

OBLIQUE-WRINKLING

Author:
Artur L. Gower

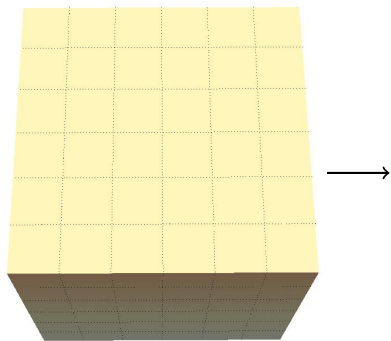
Co-Author:
Prof. Michel Destrade

National University of Ireland Galway



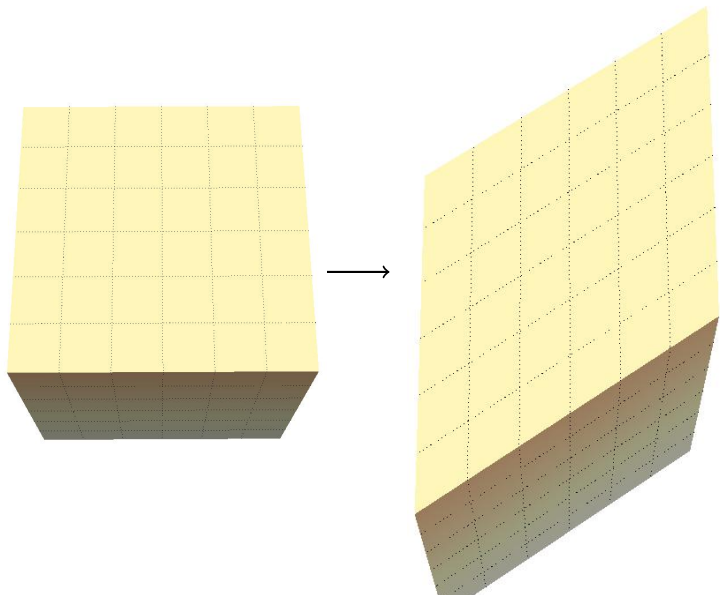
A long long time ago...

Biot in 1963 predicts,



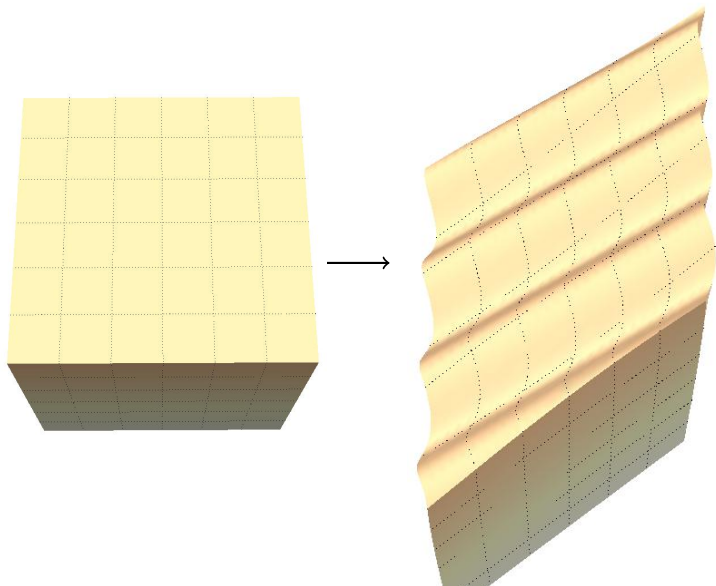
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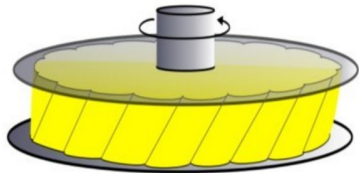
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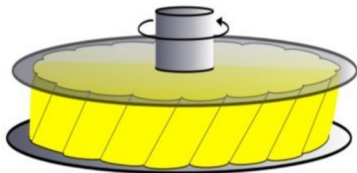
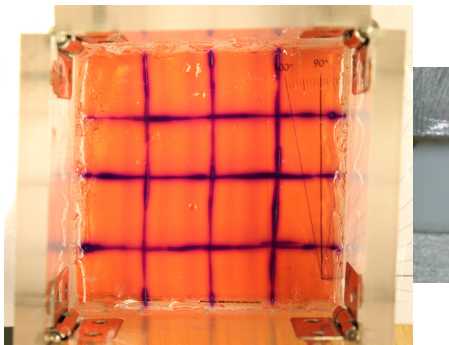
Designing an experiment



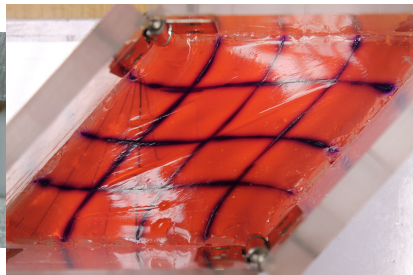
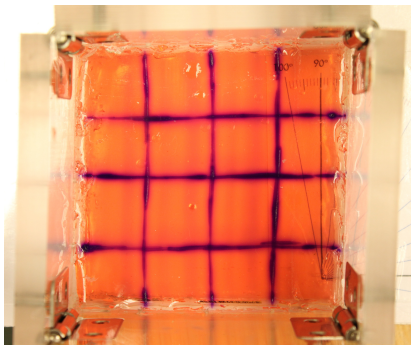
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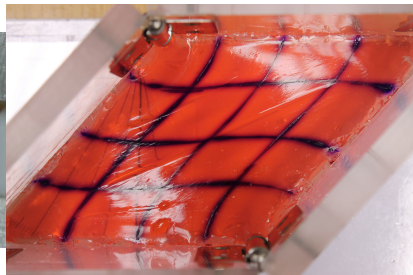
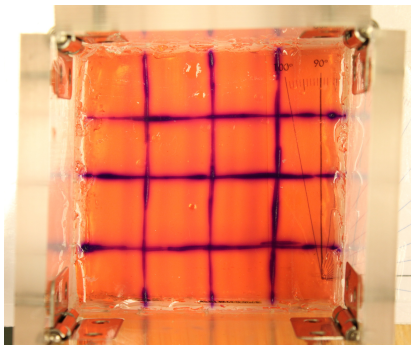
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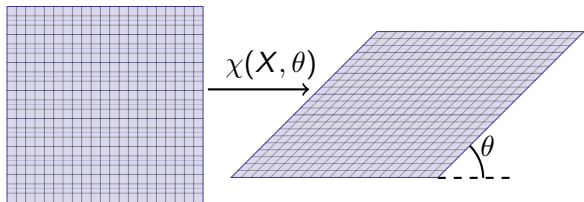
Designing an experiment



→ Maintains a more homogeneous deformation →

Theoretical Model

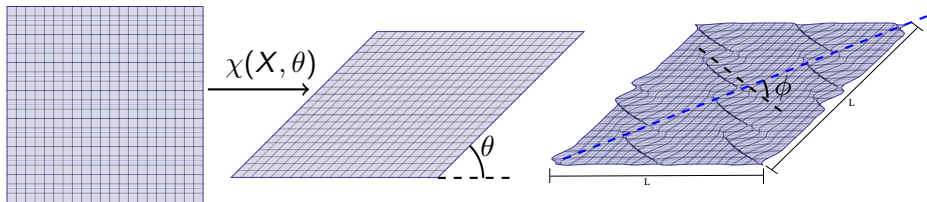
Shear-box $x = \chi(X, \theta)$



Theoretical Model

Shear-box $x = \chi(X, \theta)$ plus small $\tilde{x}_j = x_j + u_j$ with

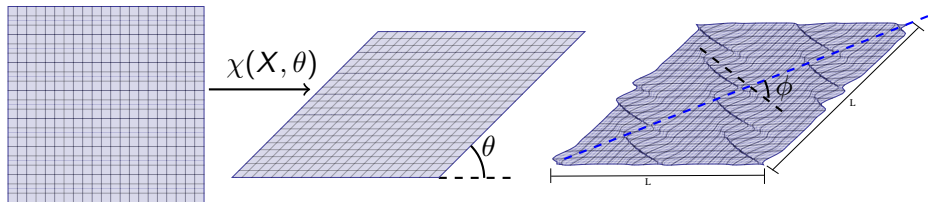
$$u_j(x, y, z) = U_j(y) e^{ik(x \cos \phi + z \sin \phi)}.$$



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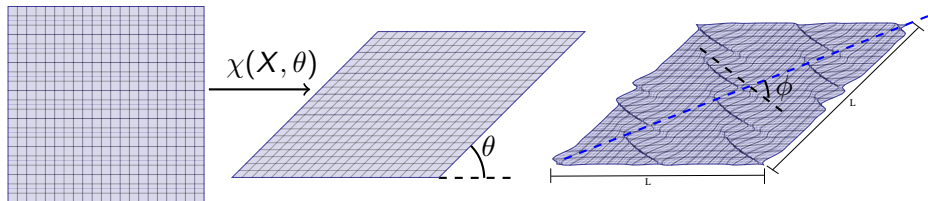


$$\underbrace{\text{div } \sigma = 0 \text{ with } \sigma_{ij} = \mathcal{A}_{jilk} u_{k,l}}_{\text{Incremental Equilibrium Equations}}$$

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$$\underbrace{\lim_{y \rightarrow \infty} u_{ij} \rightarrow 0}_{\text{Decay Condition}}$$

$$\underbrace{\sigma_{21} = \sigma_{22} = \sigma_{23} = 0}_{\text{Zero Surface traction}}$$

Theoretical Model

Mooney-Rivlin

$$W = \frac{\mu}{4} [(1 + f)(I_1 - 3) + (1 - f)(I_2 - 3)],$$

with

$$I_1 = \text{tr } F^T F \text{ and } I_2 = \frac{1}{2}(\text{tr } F^T F)^2 - \frac{1}{2}\text{tr } (F^T F)^2.$$

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 - Neo-Hookean $f = 1$, [Flavin(1963)] with $\sigma_0 = 0.296$
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■ Extreme Mooney-Rivlin $f = -1$ with the above σ_0

$$\sigma_0^4 + \sigma_0^3 + \lambda_1^2 \lambda_2^2 (\lambda_1^4 \lambda_2^4 - \lambda_2^2 - \lambda_1^2) \sigma_0 (\sigma_0 + 1) + 4\lambda_1^6 \lambda_2^6 = 0$$

Predictions

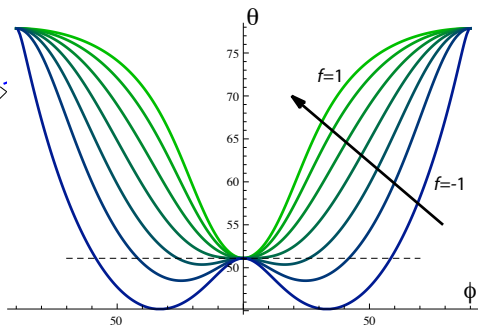
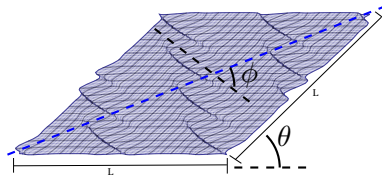
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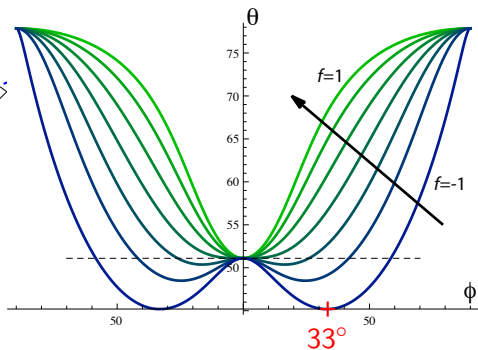
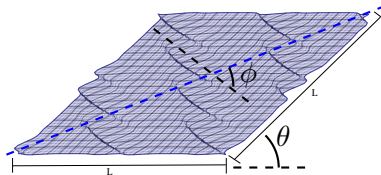
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Vague Energy Considerations

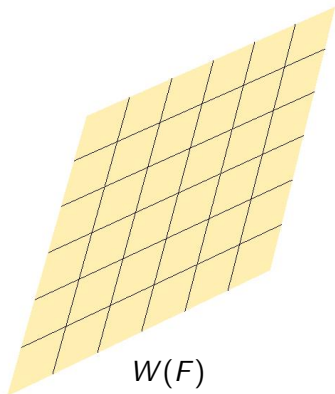
$$\min_u W(F) \implies \operatorname{div} \sigma = 0.$$

First wrinkles are not oblique when wrinkles are predominantly transverse. For example..

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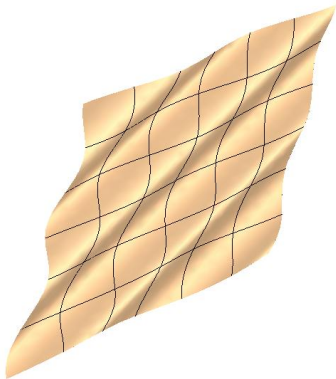
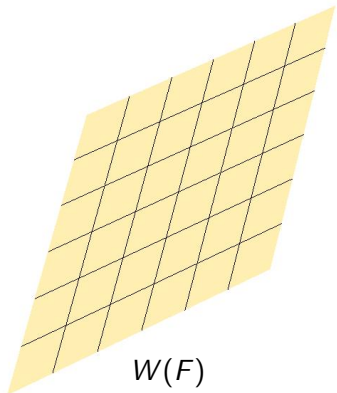
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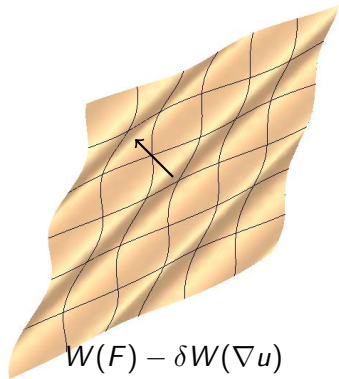
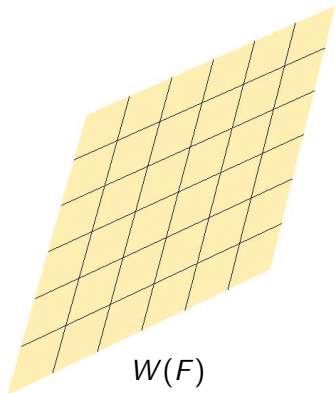
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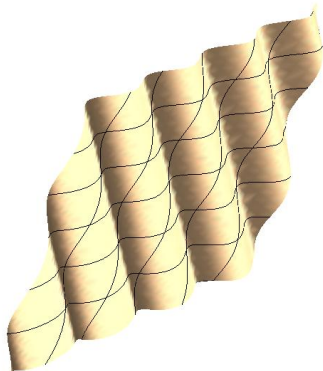
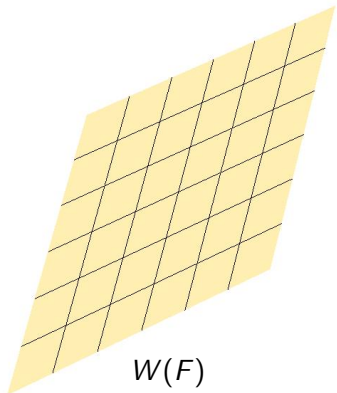
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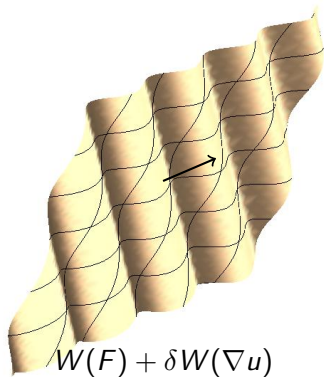
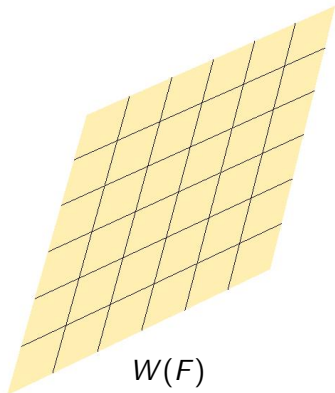
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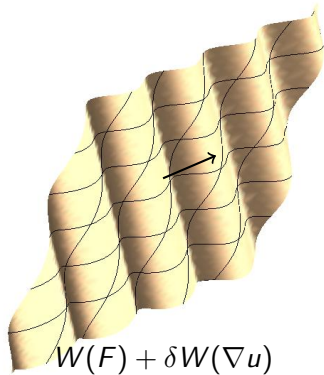
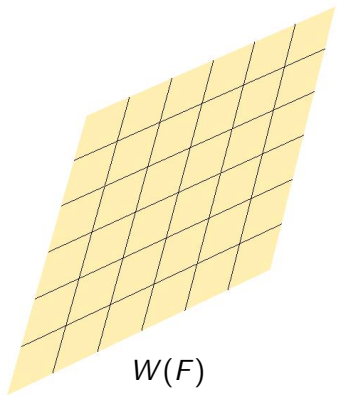
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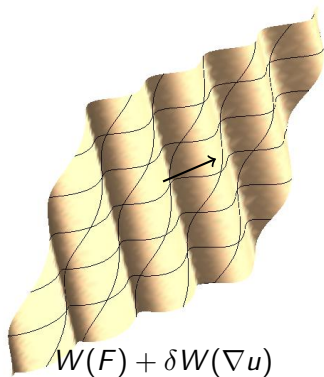
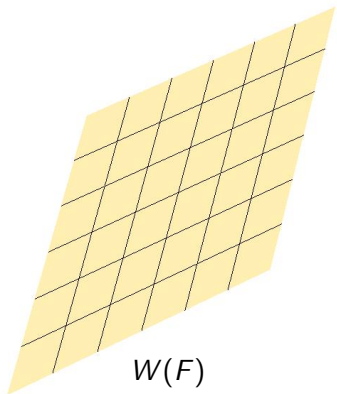
Similarly: zero traction \implies zero surface energy increment.



Vague Energy Considerations

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$$0 = u_i^* \sigma_{i2} = \mathcal{A}_{jilk} u_{i,j}^* u_{l,k} = \delta W(\nabla u), \text{ on } y = 0.$$



What next?

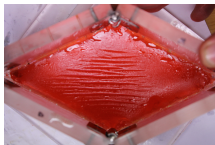
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What next?

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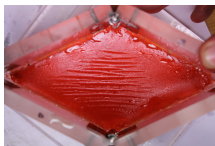
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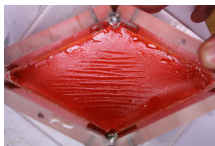
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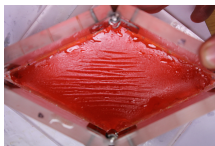
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Any questions?

Thanks for listening and hope you enjoyed the talk!

-  A.M. Biot. Surface instability of rubber in compression. Applied Scientific Research A12 (1963) 168–182. [Note that *stricto sensu*, surface instability can be traced back at least to A.E. Green & J.E. Adkins, Large Elastic Deformations (Oxford, 1960)]
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