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Phase field modeling of ductile fracture at large plastic strains using adaptive isotropic remeshing

Hazem Eldahshan^{a,b}, Pierre-Olivier Bouchard^a, José Alves^b, Etienne Perchat^b, Daniel Pino Munoz^a

^a*MINES Paris-Tech, PSL- Research University, CEMEF – Center for Material Forming, CNRS UMR 7635, BP 207, 1 rue Claude Daunesse, 06904 Sophia Antipolis Cedex, France*

^b*Transvalor SA, E-Golf Park, 950 Avenue Roumanille, 06410 Biot, France*

Abstract

In this paper, a phase field model of ductile fracture is described within the framework of large plastic strains. Most results dealing with phase field modeling of ductile fracture are carried out on a fixed mesh, which requires a fine mesh throughout all the computation. The aim of this paper is to introduce an adaptive isotropic remeshing strategy coupled with a phase field model of ductile fracture to achieve accurate results with a major decrease in computational time. A mixed velocity/pressure finite element formulation is used for the solution of mechanical fields. The plastic strain field needs to be transferred to the new mesh after each remeshing operation. This field transfer requires the use of a suitable remeshing-transfer operator. Different field transfer operators are tested and results are reported. In order to reduce the numerical diffusion associated with the field transfer operation, a volume quality based metric has been introduced. This paper presents different numerical examples with both qualitative and quantitative analyses in order to show the ability of the developed strategy in predicting crack evolution in ductile materials. The proposed framework is also able to predict crack paths in highly ductile materials while benefiting from space-adaptivity.

Keywords: Phase field model, Ductile fracture, Velocity/pressure finite element, Adaptive isotropic remeshing, Field transfer operator

1. Introduction

The phase field model for fracture was introduced in a variational form by Francfort and Marigo [1] as a generalization of Griffith's criterion to predict the critical stress for brittle fracture. The minimization of a functional that contains the sum of total elastic strain energy and fracture energy enables predicting the initiation, propagation, merging and branching of multiple cracks under complex loading conditions. Nonetheless, the original formulation is not appropriate for numerical treatment since the crack surfaces are not known a priori; hence the computational scheme becomes non-tractable in the sense that the resulting algorithm will be complicated to implement. Fortunately, this problem has been tackled in the field of image processing with the so-called Mumford-Shah functional [2] and thereafter a regularization introduced by Ambrosio and Tortorelli [3]. Bourdin et al. [4] introduced a numerical procedure based on the regularized functional that substitutes the sharp crack topology by a damaged zone with a field variable known as "phase field" that goes from 0 (intact material) to 1 (totally damaged).

14 Most of the phase field models available in the literature deal with the problem of brittle frac-
15 ture [5, 6, 7]. However, many extensions of the phase field model for ductile fracture have been
16 introduced in the literature for 2D configurations [8, 9] and also for 3D configurations with finite
17 strains [9, 10, 11, 12, 13]. Recently, a porous-ductile phase field model was introduced in [14] in
18 which the critical energy release rate is decomposed into elastic and plastic parts where the plastic
19 deformation is described by a modified GTN model [15, 16]. Unfortunately, the phase field model
20 for ductile fracture is not variationally consistent. In consequence, different options are proposed
21 in the literature on the way plastic strains can contribute to the ductile fracture in order to mimic
22 the behaviour of brittle fracture. For example, M. Ambati et al. [8] introduced a new degradation
23 function that contains the equivalent plastic strain in an exponential form. This means that the
24 material is degraded in regions where the plastic strain is localized; hence the crack propagation
25 is directly affected by plasticity. On the other hand, Borden et al. [11] added the plastic strain
26 energy along with a plastic degradation function that depends only on the phase field variable in
27 the crack driving force. A good review for the different phase field models of ductile fracture can
28 be found in [17].

29 In the current work, the model of Borden [11] is implemented in **FORGE** ®¹ where a mixed
30 velocity/pressure finite element model with a bubble function stabilization known as P1+/P1
31 is used to solve the mechanical equations using tetrahedral elements. The bubble stabilization tech-
32 nique is used in order to satisfy the Brezzi-Babuska inf-sup condition [18, 19]. The resulting finite
33 element model is able to solve the mechanical problems with large plastic strains while minimiz-
34 ing numerical instabilities. The phase field equation is solved on the same mesh. A staggered
35 algorithm is used to decouple the solution of mechanical equations from the phase field equation
36 since the resulting coupled system of equations is highly nonlinear [6]. Numerical comparisons are
37 carried out in order to validate the current numerical implementation with the original model.

38 Starting the computations with a fixed mesh that is locally refined in the areas where the phase
39 field is expected to propagate is the main strategy used in the literature to solve this problem.
40 It can be expected that two problems emerge when this strategy is applied: (i). the locations
41 of cracks need to be known a priori which is not the case in most of the applications in fracture
42 mechanics; (ii). the number of elements in the mesh becomes very large from the beginning of
43 the computations which is usually not needed before a crack is initiated, hence the computational
44 scheme becomes inefficient. In order to deal with these problems, an adaptive isotropic remeshing
45 strategy is used in order to adapt the mesh in the regions where the phase field is expected to
46 propagate. In isotropic remeshing, all edges of each element should be scaled with the same mul-
47 tiplicative factor which is suitable for our purpose. Very few attempts to use adaptive remeshing
48 strategies coupled with a phase field model in the context of brittle fracture have been reported in
49 the literature. To the extend of our knowledge, the development of an adaptive remeshing scheme
50 for the phase field model for ductile fracture has not been addressed before in the literature.

51 A multi-scale modeling approach has been adopted in [20] to keep a small mesh size around the
52 crack tip. A fine mesh structure is defined with respect to a coarse mesh topology using a multi
53 scale basis functions.

54 Another proposition of a multi level hp-FEM strategy has been adopted also in [21] for brittle
55 fracture simulations. They showed that with the developed remeshing strategy, it was possible to
56 obtain accurate numerical results as compared to the cases with a fixed mesh. The main advan-
57 tage is the great reduction in the number of degrees of freedom at the beginning of the simulation

¹FORGE ® is a finite element software specialized in material forming simulation.

58 and hence the computational time decreases significantly. In [22], a predictor-corrector refinement
59 strategy inspired by the work in [23] is presented within a global-local approach for the anisotropic
60 phase field modeling. The solution of the mechanical system is solved on a global coarse mesh
61 while the phase field solution is based on a local refined mesh. Recently, Alba Muixi et al. [24]
62 introduced a new h-refinement strategy that is based on the use of two types of elements: stan-
63 dard and refined elements where continuity is imposed in a weak sense by the means of Nitsche’s
64 method. In addition, Patil et al. [25] presented a Phase field adaptive scheme for brittle materials
65 that combines three different methods: (i). Phase field method; (ii). Extended finite element
66 method (XFEM); (iii). Multiscale finite element method. The proposed approach reduces the so-
67 lution domain to a small vicinity around the crack tip with an adaptive refinement which reduces
68 significantly the computation time.

69 In [26], a predictor-corrector remeshing strategy is implemented within the framework of brittle
70 fracture. Starting with a coarse mesh, a two-steps solution procedure is adopted: a predictor step
71 on a coarse mesh is first used to obtain initial results which is followed by a refinement step where
72 the solution is recalculated. A similar idea is used in [23], a solution is obtained at time t on an
73 initial mesh. Then, the time advances and if the crack is found to propagate outside the refined
74 zone, a refinement operation takes place while the old phase solution is interpolated on the new
75 mesh. The process is repeated until no change happens.

76 Authors in [27] introduced a computational framework known as VEM (Virtual element method)
77 as a generalization of the classical finite elements method that can be used to form any shape of
78 elements with an arbitrary number of nodes. The developed method is suitable for crack prop-
79 agation and brittle and ductile fracture simulations [28, 29]. Ali Hussein et al. [30] introduced
80 an adaptive crack simulation framework using the phase field method and the VEM in brittle
81 materials. The mesh is refined around the crack tip when the maximum value of the phase field
82 reaches some threshold which is followed by an equilibrium step using the staggered algorithm.
83 Finally, a cutting algorithm is used to split the virtual elements and open the crack faces.

84 In this paper, we generalize the remeshing operation to deal with ductile fracture where the
85 material is history dependent due to plastic deformations. Three main challenges are to be stud-
86 ied: (i). the choice of an appropriate refinement indicator function that is suitable for ductile
87 materials; (ii). the choice of a conservative field transfer operator that minimizes the numerical
88 diffusion during the transport of fields; (iii). the reduction of the number of remeshing operations
89 in order to minimize the numerical diffusion that could lead to inaccurate tracking for the crack
90 path. The ultimate goal is to have a numerical framework that is able to accurately resolve the
91 phase field equations while reducing the computational time in ductile fracture simulations. A
92 comprehensive review for the different field transfer operators can be found in [31]. The paper is
93 structured as follows: Section 2 introduces the variational formulation of the phase field method
94 for ductile fracture within the framework of velocity/pressure mixed finite element formulation.
95 Then section 3 presents the adaptive isotropic remeshing scheme used in this work. In section 4,
96 two numerical examples are presented with both qualitative and quantitative analyses. Finally, a
97 conclusion with some perspectives on the future work is drawn in section 5.

98 **2. Formulation of the problem**

99 *2.1. Original formulation*

The first step is to define a free energy functional \mathcal{E} which is a Mumford–Shah [2] type as follows

$$\mathcal{E}(\mathbf{u}, \Gamma) = \int_{\Omega_h} W_e(\boldsymbol{\varepsilon}^e) d\Omega_h + \int_{\Gamma} G_c d\Omega_h \quad (1)$$

where $\boldsymbol{\varepsilon}^e$ is the elastic strain tensor, W_e is the elastic energy density, G_c is the fracture toughness, Ω_h is the occupied volume in the reference configuration and Γ is the crack surface in the reference configuration. This energy functional is an extension of the Griffith’s definition of brittle fracture. The competition between internal elastic and fracture energies leads to the onset and propagation of cracks in materials. As can be observed, it is needed to determine a priori the fractured surface in order to calculate the fracture energy. This results in a computational scheme that is non-tractable and inconvenient to apply. To facilitate the solution of this problem, another variational formulation based on regularizing the energy functional following the work of Ambrosio and Tortorelli was introduced [3]. With this approximation, a scalar variable known as the phase field variable is added; d goes from 0 (intact material) to 1 (totally broken). The variational formulation of *brittle diffused damage* is written as

$$\mathcal{E}_l(\mathbf{u}, d) = \int_{\Omega_h} g_e(d) W_e(\boldsymbol{\varepsilon}^e) d\Omega_h + \int_{\Omega_h} G_c \mathcal{C}(d, \nabla d) d\Omega_h \quad (2)$$

where two new components are added:

$g_e(d)$ is an elastic degradation function that is defined as follows

$$g_e(d) = ((1 - d) + \zeta)^2 \quad (3)$$

and $\mathcal{C}(d, \nabla d)$ is the crack surface density that diffuses the sharp crack topology into a continuous field

$$\mathcal{C}(d, \nabla d) = \frac{1}{2l_c} (d^2 + l_c^2 |\nabla d|^2) \quad (4)$$

100 where ζ is a numerical parameter used to prevent the singularity of the stiffness matrix. Minimizing
 101 the regularized energy functional would give a differential equation that governs the evolution of
 102 the phase field in brittle materials. Miehe et al. [6, 32] proposed a thermodynamically consistent
 103 formulation to the phase field problem based on transforming the discontinuous nature of the crack
 104 to a continuous one leading to very similar mathematical formulation.

105 In order to deal with the ductile fracture problems, new components should be added to the
 106 formulation such as plastic strain, stress triaxility and Lode parameter [33]. M. ambati et al. [8]
 107 showed that although there is no variationally consistent formulation for the phase field problem
 108 of ductile fracture, it is possible to mimic the brittle fracture formulation by adding components
 109 that represent the ductility of the material. Authors proposed to couple the elastic degradation
 110 function with the equivalent strain through an exponential form. In addition, Borden et al. [11]
 111 added the plastic energy with a new plastic degradation function to the free energy functional.

112 *2.2. Phase field formulation of ductile fracture*

Following the work of [11], the plastic strain energy is added to the crack driving force \mathcal{H} where a plastic degradation function g_p is added in order to weaken the material where the plastic

deformation is localized. The strong form of the phase field evolution equation is written as

$$\begin{cases} \frac{G_c}{l_c}(d - l_c^2 \nabla^2 d) = \mathcal{H}(\underline{x}, t) & \text{(Evolution of the phase field)} & (5a) \\ \mathcal{H} = \beta_1 g'_e(d) \max_n W_e(\underline{\epsilon}^e(\underline{x}, d_n)) + \beta_2 g'_p(d) \langle W_p(\bar{\epsilon}) - W_0 \rangle & \text{(Crack driving force)} & (5b) \\ \nabla d \cdot \mathbf{n} = 0 & \text{(Neumann boundary condition)} & (5c) \end{cases}$$

the angle bracket operator is defined as follows:

$$\langle x \rangle = \begin{cases} x & x \geq 0 \\ 0 & x < 0 \end{cases}$$

113 $\bar{\epsilon}$ is the equivalent plastic strain, d is the phase field variable that varies from 0 (intact material)
 114 to 1 (totally broken), W_e is the elastic strain energy, W_p is the equivalent plastic strain energy, \mathcal{H}
 115 is the crack driving force, g_e and g_p are the elastic and plastic degradation functions, respectively.
 116 For simplicity, the plastic degradation function g_p is chosen to be the same as the elastic one
 117 represented in equation 3 as used in [11]. G_c is the fracture toughness, l_c is a predefined length
 118 scale, β_1 , β_2 and W_0 are numerical parameters used for calibrating the phenomenological model
 119 and \mathbf{n} is a unit vector normal to the surface. The Neumann boundary condition is imposed to
 120 ensure that no external source can actively create the crack. In other words, the crack evolution
 121 is governed by the evolution of other mechanical fields.

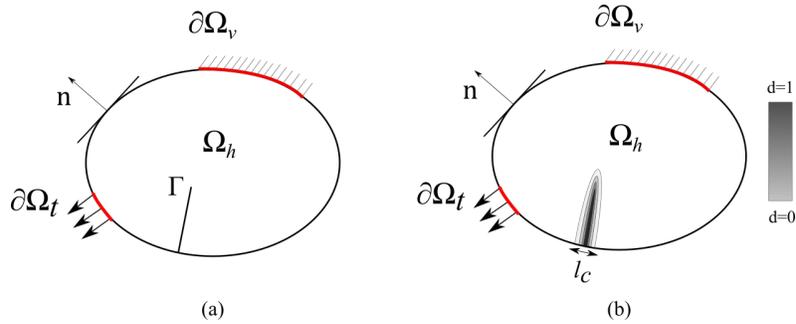


Figure 1: *a.* Geometry and boundary conditions of an arbitrary domain with discontinuity Γ . *b.* Transformation of the crack to a diffused damage with the phase field d that goes from 0 to 1.

122 2.3. Mechanical behaviour at large strains

123 main formulations are used in order to deal with large strain nonlinear problems within the
 124 context of finite element analysis: (i). Total lagrange formulation; (ii). Updated lagrange formu-
 125 lation [34, 35]. In order to deal with the problem of large plastic strains, an updated lagrangian
 126 formulation coupled with adaptive remeshing is used. With the updated lagrange formulation,
 127 the new reference configuration is set to be the deformed configuration of the last time step. In
 128 consequence, a continuous update of the geometry coordinates necessitates adaptive remeshing
 129 operation in order to conserve the quality of elements used throughout the simulation.

130 2.4. Mechanical constitutive law

131 An elasto-plastic constitutive material law is considered. Applying the phase field model without
 132 any special treatment for crack evolution in the regions where compressive stresses exist have
 133 shown unrealistic interpenetration of crack lips. Bourdin et al. have already demonstrated with
 134 numerical examples in [4] this problem.

Decomposing the elastic strain energy into positive and negative parts while degrading solely the positive part seems to solve the aforementioned problem. The final form of the elastic energy can be decomposed as

$$W_e(\boldsymbol{\varepsilon}^e) = g_e(d)W_e^+(\boldsymbol{\varepsilon}^e) + W_e^-(\boldsymbol{\varepsilon}^e) \quad (6)$$

where W_e^+ and W_e^- are the positive and negative parts of the elastic strain energy, respectively.

The approach introduced by Amor et al. [36] for the energy decomposition is used as follows:

$$\begin{aligned} W_e^+(\boldsymbol{\varepsilon}^e, d) &= \frac{\kappa}{2} \langle \text{tr}(\boldsymbol{\varepsilon}^e) \rangle_+^2 + \mu \boldsymbol{\varepsilon}_{dev}^e : \boldsymbol{\varepsilon}_{dev}^e \\ W_e^-(\boldsymbol{\varepsilon}^e, d) &= \frac{\kappa}{2} \langle \text{tr}(\boldsymbol{\varepsilon}^e) \rangle_-^2 \end{aligned} \quad (7)$$

where $\boldsymbol{\varepsilon}_{dev}^e = \boldsymbol{\varepsilon}^e - \frac{\text{tr}(\boldsymbol{\varepsilon}^e)}{3}$, $\mu = \frac{E}{2(1+\nu)}$, E is the Young's modulus, ν is Poisson's ratio and κ is the bulk's modulus.

where

$$\langle x \rangle_+ = \begin{cases} x & x \geq 0 \\ 0 & x < 0 \end{cases} \quad \langle x \rangle_- = \begin{cases} 0 & x \geq 0 \\ x & x < 0 \end{cases}$$

The first part of the positive elastic strain energy W_e^+ replaces the total strain energy W_e that appears in equation 5b. The positive elastic energy W_e^+ contains a volumetric part that reflects the effect of dilatation along with the deviatoric part that reflects the effect of shear deformation. The positive elastic strain energy enters in competition with the fracture energy resulting in the evolution of the phase field.

On the other hand, the negative part of the elastic energy density that is related to reduction in volume does not contribute to the evolution of the phase field. The resulting constitutive relation is shown as

$$\boldsymbol{\sigma} = \kappa(1 - \alpha d)^2 \text{tr}(\boldsymbol{\varepsilon}^e) + 2(1 - d)^2 \boldsymbol{\varepsilon}_{dev}^e I^{dev} \quad (8)$$

where

$$\alpha = \begin{cases} 1 & \text{tr}(\boldsymbol{\varepsilon}^e) > 0 \\ 0 & \text{else} \end{cases}$$

136 and $I_{ijkl}^{dev} = I_{ijkl} - \frac{1}{3}\delta_{ij}\delta_{kl}$, $I_{ijkl} = \frac{1}{2}(\delta_{ij}\delta_{kl} + \delta_{ik}\delta_{jl})$ with δ the Kronecker's delta.

The return mapping algorithm is used to update the equivalent plastic strain and deviatoric Cauchy stress tensor at each time step, with the assumption of no plastic deformation increment, the resulting equations can be written as

$$\mathbf{s}^{trial} = 2\mu g_e(d_n) [\boldsymbol{\varepsilon}_{n+1} - \boldsymbol{\varepsilon}_n^p] \quad (9a)$$

$$f^{trial} = \boldsymbol{\sigma}_{VM} - g_p(d_n)\boldsymbol{\sigma}_0(\bar{\boldsymbol{\varepsilon}}_n) \leq 0 \quad (9b)$$

where

$$\boldsymbol{\sigma}_{VM} = \sqrt{3 J_2(\mathbf{s}_{n+1}^{trial})} \quad (10)$$

where \mathbf{s}^{trial} is the trial deviatoric stress, $\boldsymbol{\varepsilon}$ is the total strain tensor and $\boldsymbol{\varepsilon}^p$ is the plastic strain tensor, J_2 is the second invariant of the deviatoric stress tensor and n is the increment number. If condition 9b is not satisfied, a new plastic deformation increment is found as follows

$$f = \sqrt{3 J_2(\mathbf{s}_{n+1}^{trial})} - g_p(d_n)\boldsymbol{\sigma}_0(\bar{\boldsymbol{\varepsilon}}_{n+1}) - 3\mu g_p(d_n)\Delta\lambda = 0 \quad (11)$$

where λ is the plastic multiplier. The effective stress is defined as follows

$$\boldsymbol{\sigma}_0 = \sigma_y + H\bar{\boldsymbol{\varepsilon}} \quad (12)$$

where σ_y is the initial yield stress and H is the plastic modulus. It should be noted that d_n is constant in equation 11. A Newton-Raphson nonlinear solver is used to solve equation 11, the plastic strain update is written as

$$\bar{\boldsymbol{\varepsilon}}_{n+1} = \bar{\boldsymbol{\varepsilon}}_n + \Delta\lambda \quad (13)$$

The update of the deviatoric stress tensor and discrete tangent modulus are expressed as follows

$$\mathbf{s}_{n+1} = \frac{\mathbf{s}_{n+1}^{trial}}{1 + \frac{3\mu g_e(d_n)\Delta\lambda}{\boldsymbol{\sigma}_0(\bar{\boldsymbol{\varepsilon}}_{n+1})}} \quad (14)$$

$$C_{n+1}^d = \frac{\partial \dot{\mathbf{s}}^{n+1}}{\partial \dot{\boldsymbol{\varepsilon}}^{n+1}} = 2\mu g_e(d_n) \left(1 - 6 \frac{\mu^2 \Delta\lambda}{J_2(\mathbf{s}_{n+1}^{trial})} \mathbf{I}^{dev} \right) - 4\mu^2 \bar{\mathbf{n}} \otimes \bar{\mathbf{n}} \left(\frac{1}{\frac{\partial \boldsymbol{\sigma}_0}{\partial \delta\lambda} + 3\mu g_e(d_n)} + \frac{\Delta\lambda}{J_2(\mathbf{s}_{n+1}^{trial})} \right) \quad (15)$$

138 where $\bar{\mathbf{n}} = \frac{3}{2} \frac{\mathbf{s}}{J_2(\mathbf{s}_{n+1})}$ and \otimes is the tensor product.

139 3. Adaptive isotropic remeshing

140 The most used strategy in the literature to deal with the phase field model is to use a fixed mesh
 141 with local refinement. The minimum element size h_{min} should be chosen in order to properly
 142 describe the damage zone. However, a larger element size can be used at the beginning of the
 143 simulation before starting the damage initiates. As recommended by Miehe et al. [6], h_{min} in the
 144 critical zones where the crack is expected to propagate is chosen to be two times less than the
 145 length scale l_c . Two main problems arise with that choice: (i). the element size is not necessary
 146 to get accurate results before damage occurs, which leads to high unnecessary computational cost;
 147 (ii). the fact that the mesh size should be refined before starting the computations contradicts the
 148 purpose of our model which is to predict the location of crack initiation and propagation.

149 In this article, an adaptive scheme is adopted to generate new meshes that are refined in the
 150 regions where the phase field is expected to propagate. The originality of the current work comes
 151 from the applicability of the developed tools to deal with both brittle and ductile fracture patterns
 152 using the phase field model. Three main challenges exist with the adopted remeshing strategy:
 153 (i). controlling the number of remeshing operations until the final geometry is obtained; (ii). the
 154 choice of an indicator function that triggers the remeshing process; (iii) the choice of a consistent
 155 field transfer operator that minimizes the numerical diffusion after each remeshing step.

156 Elements are refined upon reaching a given threshold for a given indicator function that can be
 157 tailored numerically. A tag for each element is used to know whether or not it needs to be refined
 158 during the computations.

Numerical diffusion during remeshing is inevitable. Thus, the solution will be more conservative as the number of remeshing operations is reduced. Once a sufficiently refined mesh is obtained, the remeshing process should be terminated. In order to achieve that objective, another indicator function is proposed that is based on a volume quality metric. The volume quality metric is defined as the ratio between the new and old volumes of each element. At each increment, the new volume of each element is calculated based on the nodal values of the phase field. For example, if the smallest volume quality among all elements of the new mesh exceeds a given threshold, a remeshing step is carried out. Otherwise, no remeshing step is done. Fig. 2 illustrates the way of calculating the element size. The size related to the phase field value at each node is determined based on the value of the phase field, i.e., the size only changes if the phase field value exceeds the pre-set threshold. At each increment, a volume quality metric \mathcal{B} is calculated for each element T as follows

$$\mathcal{B}(T) = \min\left(\left(\frac{l_{new}}{l_{old}}\right)^3, \left(\frac{l_{old}}{l_{new}}\right)^3, \frac{V_{\Omega_1}}{V_{Ref}}\right) \quad (16)$$

where l_{new} is the average length of a tetrahedron in the new mesh in case of remeshing, l_{old} is the average length of a tetrahedron in the old mesh, V_{Ω_1} is the volume of a tetrahedron in the old mesh and V_{Ref} is the volume of a reference equilateral element of the same average length as the element of the new mesh in case of remeshing.

The mesh quality threshold can be chosen to be as follows

$$\text{Mesh quality threshold} = \left(\frac{l_f}{\eta l_0}\right)^3 \quad (17)$$

160 where l_f is the pre-set element size in the refined zone in which the phase field is expected to
 161 propagate, l_0 is the element size of the initial mesh and η is a numerical parameter that varies
 162 between 0.6 and 1.4. This artificial parameter η gives some tolerance for the remeshing initiation
 163 process as the initial element size distribution is heterogeneous. The proposed threshold gives an
 164 upper bound for the ratio of element volume between the old and new meshes.

165 This proposed mesh quality metric is essential in limiting data diffusion due to remeshing. In
 166 other words, the rule here is that: once the region in which the crack is expected to propagate is
 167 remeshed, the remeshing is terminated.

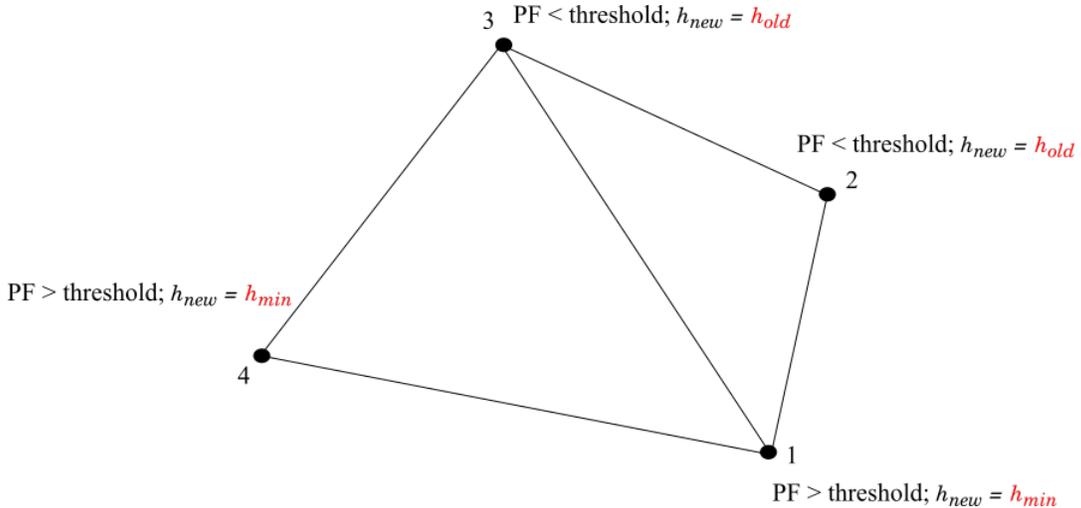


Figure 2: Calculating the new element size based on the phase field values at the nodes.

168 3.2. Field transfer operator

169 Field transfer operation refers to the transport of fields between two different topologies repre-
170 senting the same geometrical space. Regardless of the method used in this step, an amount of
171 data is always lost due to the non-exact transfer of fields. The main features of a conservative
172 remeshing-transfer operator are: (i). Minimizing the numerical diffusion; (ii). Preserving the me-
173 chanical equilibrium. Two types of fields can be transferred, nodal fields and fields that are stored
174 at the integration points. For the updated lagrangian formulation that is used in this study, both
175 the nodal fields and the fields that are stored at the integration points will be interpolated to the
176 new mesh.

177 Two categories of transfer operator will be used for the sake of demonstration: (i). P0 transfer:
178 each integration point in the new mesh takes the value of its nearest neighbourhood in the old
179 mesh; (ii) P1 transfer: A three-step procedure is carried out (i). A smoothing operator transforms
180 the field stored at the integration points to a nodal field; (ii). A direct interpolation maps the nodal
181 fields of the old mesh to the new mesh; (iii). The continuous field at the new mesh is remapped
182 to the integration points [37, 38].

183 Different remeshing transfer operators are introduced in the literature. Sushil Kumar et al. [31]
184 presented a comparison between a wide categories of methods related to the recovery by element
185 patches and recovery by nodal patches. Authors have shown that increasing the interpolation order
186 of the transfer operator increased the accuracy and convergence behaviour by the same order. In
187 [39], a continuous solution is given in the vicinity of a given integration point that is considered
188 to be valid for a patch of elements. Then, the value is used for the element of the new mesh that
189 contains this integration point. Likewise, Zienkiewicz and Zhu presented in [40] the SPR (Super
190 convergent Patch Recovery) method which is based on retrieving a mapped stress field using a
191 patch of elements sharing a common node. In order to ensure the equilibrium after each remeshig
192 operation, a few Newton-Raphson iterations need to be carried out as suggested in [41]. Authors
193 in [42] propose to divide the loading step just after the remeshing operation to two steps in order
194 facilitate the convergence while ensuring the equilibrium. Another proposition in [31, 43] is to
195 ensure that the transferred field preserves the equilibrium at the new mesh.

196 In this article, for the sake of simplicity, two field transfer operators are tested: i. Nearest point
197 interpolation method; ii. P1 transfer by Galerkin smoothing method.

198 3.2.1. P0 transfer method (Nearest point interpolation)

199 This method is the simplest one among the other field transfer operators. However, it lacks a
200 proper mathematical consistency when compared to other methods so that it can be very diffusive
201 if the mesh is not very refined. The values of P0 fields (constant per element) are transferred
202 directly from each integration point of the old mesh to the nearest new point in the new mesh as
203 shown in Fig. 3a. This technique has the advantage of preserving the values of the transferred
204 field when the changes in the mesh topology are very small. However, the remapping error is
205 proportional to the field gradient, i.e., when the gradient of a given field is very high, it becomes
206 very difficult to recover the fields with high accuracy. This technique also has the advantage of
207 a low computational cost since no additional operations are done except for locating the nearest
208 neighbourhood of each integration point in the mesh. Fig. 3a summarizes the steps of this method.

209 3.2.2. P1 transfer with Galerkin smoothing

The Galerkin smoothing method is referred to the smoothing of discontinuous P0 fields in order to
build another continuous P1 field per element. This means that at each time step the P0 fields are

transformed to be P1 fields followed by a direct nodal interpolation using the same interpolation functions used for the finite element solution as shown in Fig 3b. Finally, a P0 field is recovered from the constructed P1 field. The main advantage of this method is that it is expected to be more conservative than the nearest point interpolation method when the old and new mesh typologies are very different. On the contrary, it should always be expected to have an amount of data loss due to the P0-P1-P0 transformations even if the mesh topological changes are small.

Let us consider a given discontinuous field g_{P0} that is calculated on an old mesh and the new continuous field calculated at the element nodes f_{P1} . Recovering the same field at the nodes requires that

$$f_{P1} = g_{P0} \quad (18)$$

since the condition cannot be strongly applied due to the nature of the two functions, transforming the equation into a weak form and minimizing the residual using the Galerkin smoothing method would be a possible solution. The weak form applied over an element gives

$$\int_{\Omega_h} \phi_h f_{P1} d\Omega = \int_{\Omega_h} \phi_h g_{P0} d\Omega \quad (19)$$

where ϕ_h is a test function. The functions f_{P1} and ϕ_h are defined as follows

$$f_{P1} = \sum_{k=1}^{N_n} N_l^k \hat{f}_{P1}^k \quad (20a)$$

$$\phi_h = \sum_{k=1}^{N_n} N_l^k \hat{\phi}^k \quad (20b)$$

210 where N_l^k are the same basis functions used in the finite element model in appendix A.

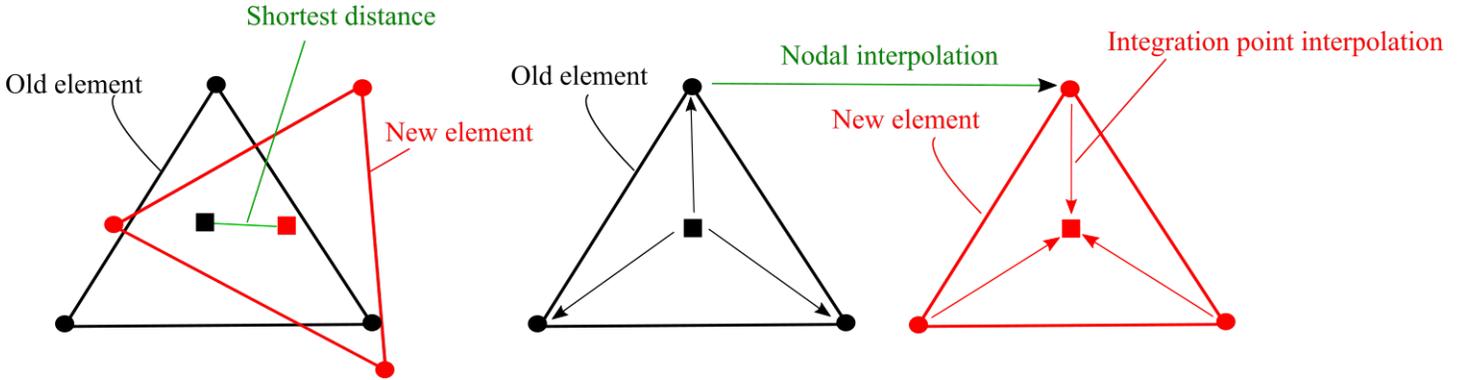


Figure 3: Field interpolation method: **a.** P0 transfer (Nearest point interpolation. **b.** P1 transfer with Galerkin smoothing.

211 The resulting finite element system is solved. In the smoothing step, a nodal interpolation step
 212 is done in order to find the field values at the new nodes. Then, another interpolation is done to
 213 find the field value at a single integration point at the barycentre of the element.

214 3.3. Summary

215 A summary of the developed method is presented in algorithm 1.

Result: $\vec{v}_{t=0:T}, p_{t=0:T}, d_{t=0:T}$

1. Initialize \vec{v}_t, p_t and d_t ;

for $t = 0 : T$ **do**

- $i \leftarrow 0, \vec{v}_i \leftarrow \vec{v}_t, p_i \leftarrow p_t$;
2. **while** ($Res_1 > Tol_{NR}$ and $i < i_{max}$) **do**
 - Solve the system of equations 27a, 27b and 27c using a Newton Raphson solver to obtain v_{i+1}, p_{i+1} ;
 - Compute the new plastic strain increment using equations 9, 11 and 13;
 - $i \leftarrow i + 1$

end

- $v_t \leftarrow v_i$;
- $p_t \leftarrow p_i$;

3. Compute $\mathcal{H}(\underline{x}, t)$ based on the new elastic and plastic strains using equation 5b;
4. Solve equation 27d with $\mathcal{H}(\underline{x}, t)$ to obtain $d_{t+\Delta t}$;
5. Check if the phase field value at each node exceeded the threshold;
6. compute new element size;
7. Check the volume quality for each element in the mesh.;
- if** ($Minimum\ mesh\ quality < Mesh\ quality\ threshold$) **then**
 8. Trigger remeshing and transport the mechanical fields;
- else**
 - Go to step 2;

end

end

217 4. Numerical results and validation

218 4.1. Symmetrically notched tension test

219 In this section, numerical validation of the implementation of Borden et al. [11] is done.
 220 The validation step is carried out with a fixed mesh. Fig. 4 shows the geometry and boundary
 221 conditions of a symmetrically notched tension test. A sensor is also placed at the middle of the
 222 distance between the two notches to trace the evolution of the phase field variable at different
 223 deformation levels. The material parameters used are: $E = 68.8$ GPa, $\nu = 0.33$, $\rho = 2700$ kg/m³,
 224 $\sigma_y = 320$ MPa, $H = 688$ MPa. The model parameters are: $\beta_1 = \beta_2 = 1$, $l_c = 0.6452$ mm
 225 $G_c = 60$ kJ/m² and $\zeta = 10^{-3}$.

226 In order to choose a suitable time step for performing the calculations, a convergence study is done
 227 with a plastic energy threshold $W_0 = 10$ MPa and results are illustrated in Fig. 5. Normalized
 228 stress refers to the applied force divided by the initial area of the narrowest cross section and
 229 normalized strain is the total displacement divided by the initial length of the specimen. From
 230 the results shown in Fig. 5, a time step of 0.05 sec is used for all subsequent simulations since it
 231 provides a good compromise between quality of results and CPU time. At the same time, one can
 232 observe that in the linear regime, the Normalized stress vs. Normalized strain curves are almost
 233 identical to the reference solution and hence a larger time step can be used without losing the
 234 solution accuracy.

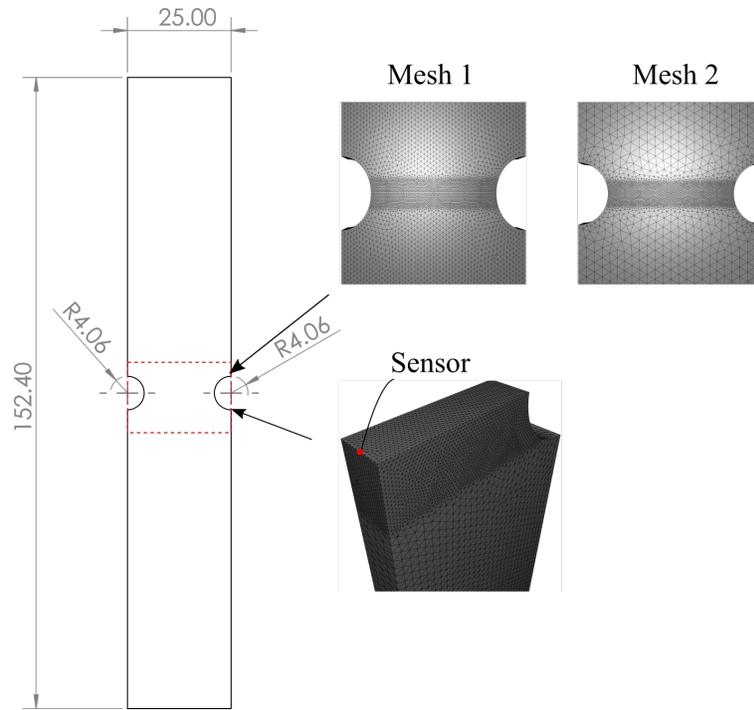


Figure 4: The representation of the tension test geometry and boundary conditions of a reference case [11]. The mesh is illustrated with the local refinement. The thickness of the specimen is 2.37 mm where all dimensions are in mm.

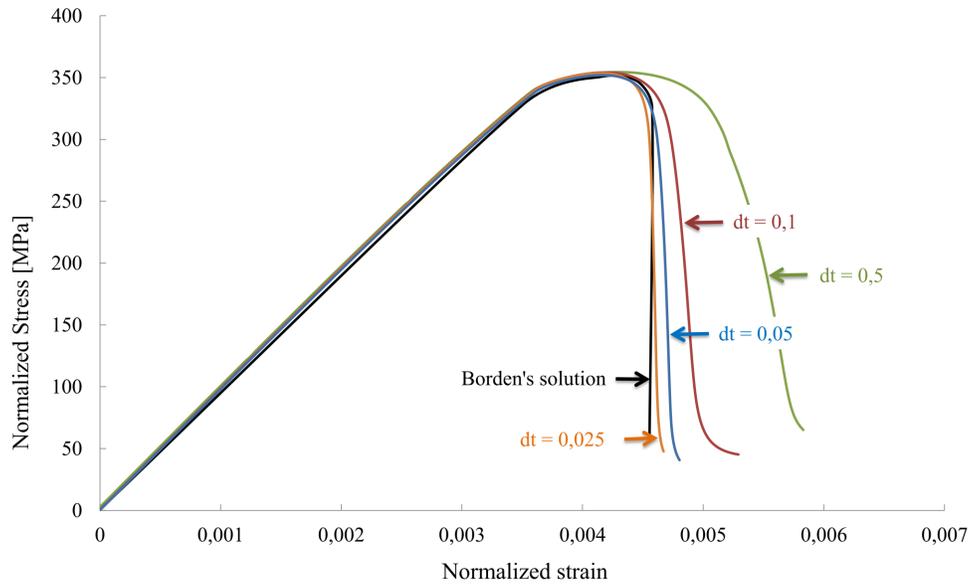


Figure 5: Study of the time step convergence for the Normalized Stress vs. Normalized Strain curves. Time increments are in seconds.

235 Fig. 6 shows a comparison with the implementation of [11] of the normalized stress vs. normal-
 236 ized strain curves for two different values of the plastic threshold W_0 . The curves are very close to
 237 the reference solution especially for $W_0 = 10$ MPa. It can be observed that there is a small shift
 238 between the curves of the current work and reference solution. This is most likely related to the

239 type of spatial discretization used for the numerical simulations which is different than the one
 240 used in [11]. For the reference case, the computations were performed using a quadratic NURBS
 241 isogeometric spatial discretization [44] whereas in the present work a tetrahedral element is used.
 242 Fig. 7 also shows the crack evolution for different values of the plastic threshold. One can clearly
 243 observe that the phase field profile at the initiation phase depends on the threshold and hence it
 244 should be well calibrated in order to accurately track the crack evolution.

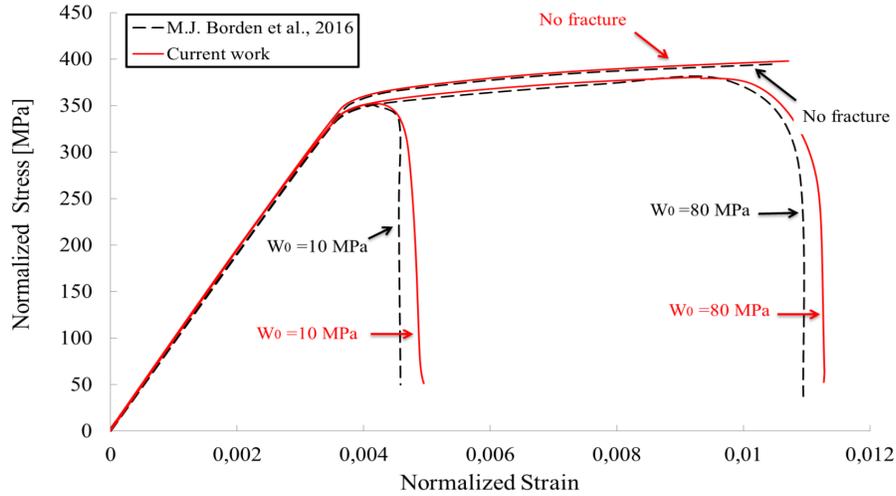


Figure 6: Numerical validation with the model of M.J. Borden et al. [11]. Results are reported for two different values of the plastic threshold. The time step is set to 0.5 sec during the first 125 steps in the linear regime then 0.025 sec for the rest of the simulation.

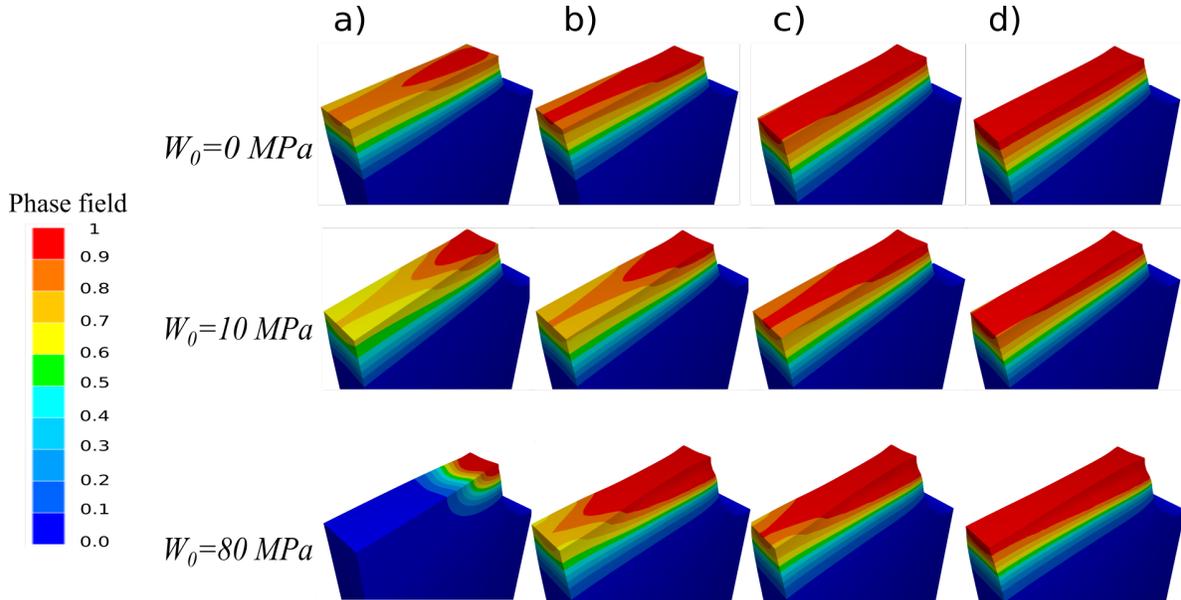


Figure 7: Contour plots of the phase field evolution for three different values for the plastic threshold W_0 . Four different deformation states are illustrated starting from crack initiation at (a) until the final failure at (d).

245 *4.2. Double-edge symmetric tension test with remeshing*

246 In this example, we show the numerical results of the phase field model obtained with the developed
 247 isotropic remeshing strategy. When remeshing is used, a constant mesh size is used in the whole

248 initial domain. Then, a mesh refinement process is carried out in order to have a small enough
249 element size in the regions in which the crack is expected to propagate. Two different base element
250 sizes are compared for the values 0.5 mm and 1.25 mm. The numerical computations are carried
251 out with two different base mesh sizes in order to illustrate the accuracy of the two field transfer
252 operators. Results are compared with a reference case of an initial fixed mesh with local refinement
253 as shown in Fig. 4. The same geometry and material properties as in section 4.1 with a plastic
254 work threshold equals to 10 MPa are used in all the simulations. Two fixed size meshes, mesh 1
255 and mesh 2, are used to compare the results with the cases where remeshing is adopted 4. Mesh 1
256 and mesh 2 have sizes of 0.5 mm and 1.25 mm in the domain, respectively. A minimum mesh size
257 of 0.1613 mm is used in the region where the crack is expected to propagate. The specimen is fixed
258 from the bottom and displaced from the upper end with a constant velocity of 0.0042 mm/sec.
259 Two different thresholds of the phase field indicator function are used: 0.025 and 0.075.

260 Fig. 8 shows the phase field evolution at four different strain states with the phase field
261 threshold value equals to 0.025 and base mesh size set to 0.5 mm. The time step is set to 0.5 sec
262 for the first 125 increments since accurate results can be obtained in the linear regime with a large
263 time step and then 0.05 sec for the rest of the simulation since it is concluded from the time step
264 convergence study that the proposed time step is a good compromise between accuracy and low
265 computational time. The results are plotted on the current configuration where the mesh topology
266 at the different states is shown. In Fig. 8a, the remeshing is not yet initiated since this is a very
267 early deformation state, i.e., the same phase field distribution is obtained. Then, the remeshing
268 operation is initiated with both transfer operators as shown in Fig. 8b.

269 The phase field profiles with a threshold value of 0.075 are shown in Fig. 9. Comparing Figs.
270 8c and 9c shows that when the phase field threshold is 0.075, the crack initiates and propagates
271 at a larger displacement than the case of a threshold of 0.025. This can be explained by the fact
272 that when the elements size in the damaged region are not sufficiently fine, the accuracy of the
273 mechanical fields evolution is affected. In other words, when the remeshing initiation is a lightly
274 delayed, the exact moment of crack initiation is not accurately captured. In consequence, the full
275 crack is formed at a displacement $u = 0.3671$ mm which is also higher than the case when the
276 threshold is 0.025 as it is reported as $u = 0.3650$ mm.

277 It can also be observed in Fig. 9c that the crack propagates for a longer distance toward the
278 center at the same displacement when the Galerkin smoothing method is used. The reason for that
279 is also related to the field transfer operation that affects the accuracy of the transported fields.

280 Fig. 10 shows the Normalized Stress vs. Normalized Strain curves for different threshold values.
281 Results are obtained for both field transfer operators and compared with the case of an initial fixed
282 mesh. When the value of the threshold is increased to 0.075, the coarse mesh topology before the
283 initiation of the remeshing operations does not permit to capture the localized plastic strains at an
284 early stage of the deformation and hence the crack initiation is delayed. Locally, Fig. 14a shows
285 the local phase field evolution at a node shown in Fig. 4. It can be clearly observed that there is
286 a small difference in the phase field profile between the remeshing and the reference cases.

287 The number of elements and run time ² are reported in table 1. It can be clearly observed that
288 the number of elements in the end of simulations is even lower than the reference case since it is
289 difficult to know where exactly the refinement should take place so we tend to enlarge the region.

²The calculations are carried out using 6 processors on a workstation with an Intel® core™ i7-8700 CPU @ 3.2 GHz and a 32 GB RAM

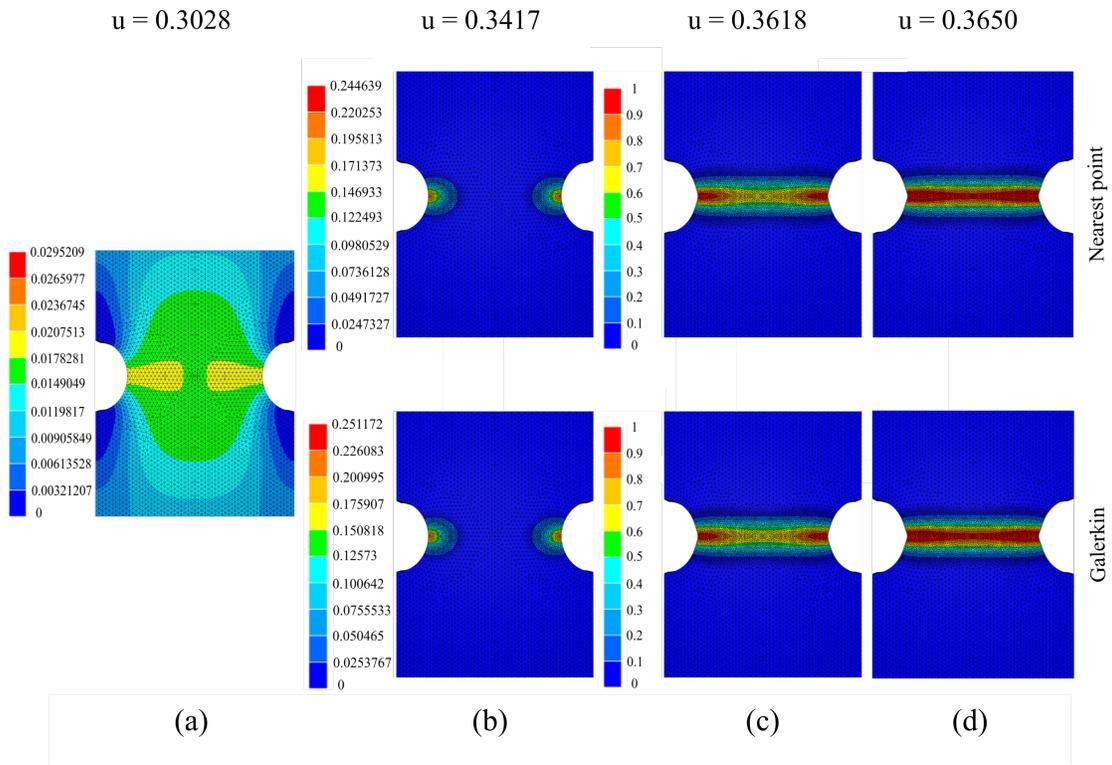


Figure 8: Evolution of phase field at different deformation states on the deformed configuration for a phase field threshold is set to 0.025. **a.** $u = 0.3028$ mm. The average element size of the base mesh is set to 0.5 mm. **b.** $u = 0.3417$ mm. **c.** $u = 0.3618$ mm. **d.** $u = 0.3650$ mm.

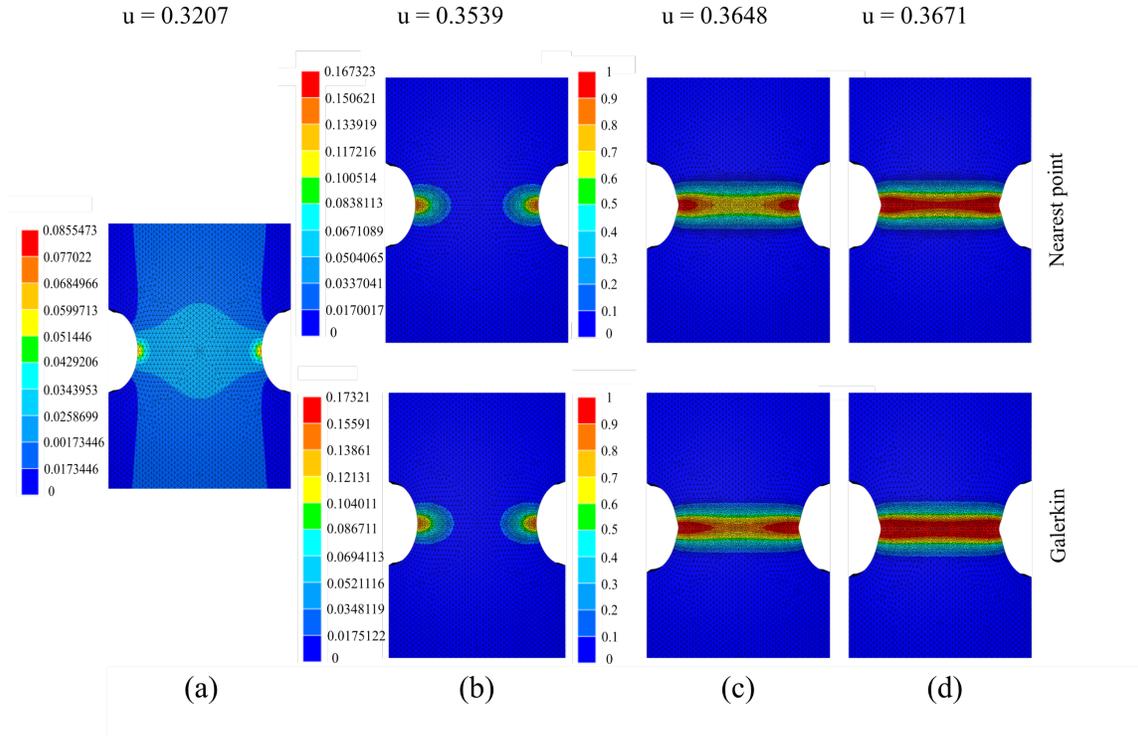


Figure 9: Evolution of phase field at different deformation states on the deformed configuration for a phase field threshold is set to 0.075. The average element size of the base mesh is set to 0.5 mm. **a.** $u = 0.3207$ mm. **b.** $u = 0.3539$ mm. **c.** $u = 0.3648$ mm. **d.** $u = 0.3671$ mm.

290 of the refined mesh.

291 To conclude, the developed adaptive remeshing strategy results in a very accurate prediction
292 of the crack initiation and propagation with a significant reduction in the computation time. It
293 should be noted that the reduction factor in the element size from the beginning to the end of
294 the computations was about 3 times. The next step is to test the model validity with a higher
295 reduction ratio. A base element of size 1.25 mm is used with a reduction ratio to the final element
296 size of about 7.75. Figs. 11 and 12 show the phase field evolution profiles for two threshold values
297 of 0.025 and 0.075, respectively.

298 In a general sense, for both threshold values the crack is initiated at a larger displacement than
299 the cases with a base element size 0.5 mm. It can be observed again that displacements starting
300 at the crack initiation until the complete failure are higher when the threshold 0.075 is used.

301 The same conclusion is drawn regarding the two field transfer operators; the crack propagates
302 for a longer distance at the same displacement when the Galerkin smoothing method is used as
303 shown in Figs. 11c and 12c.

304 The Normalized Stress vs. Normalized Strain curves are shown in Fig. 13. From a global view,
305 there is a the shift between the curves of fixed mesh and remeshing cases as compared to the case
306 with a base element size of 0.5 mm. It can be also observed that when a threshold of a value 0.025
307 is used, closer results to the reference solution are obtained. The behavior of the global response
308 can be explained by the local evolution of the phase field as shown in Fig. 14b.

309

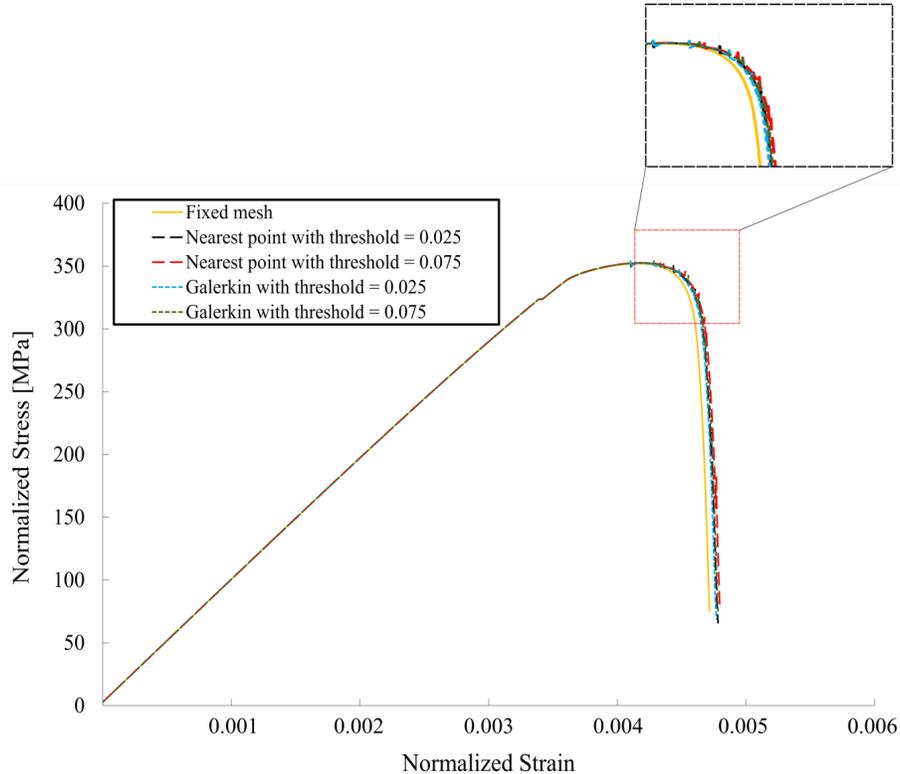


Figure 10: Symmetrically notched specimen tension test. **a** Normalized Stress vs. Normalized Strain curves for two different values for the phase field threshold. A comparison is shown for the two field transfer operators with the reference case with an initial fixed mesh. The base element size = 0.5 mm.

Table 1: Symmetrically notched tension test with base element size = 0.5 mm.

Transfer operator	Threshold	Remeshing operations	Initial number of elements	Final number of elements	CPU run time [hour]
Fixed mesh			112080	112080	1.09
Galerkin smoothing	0.025	6	82477	125550	0.85
Galerkin smoothing	0.075	6	82477	111800	0.79
Nearest point	0.025	7	82477	130800	0.77
Nearest point	0.075	6	82477	117780	0.71

310 The initial and final number of elements along with the CPU run time are reported in table 2.
 311 It can be clearly seen that the initial and final number of elements are less than the case with a
 312 base element size of 0.5 mm, i.e., the computational time has drastically been reduced by a factor
 313 of nearly 4 in average.

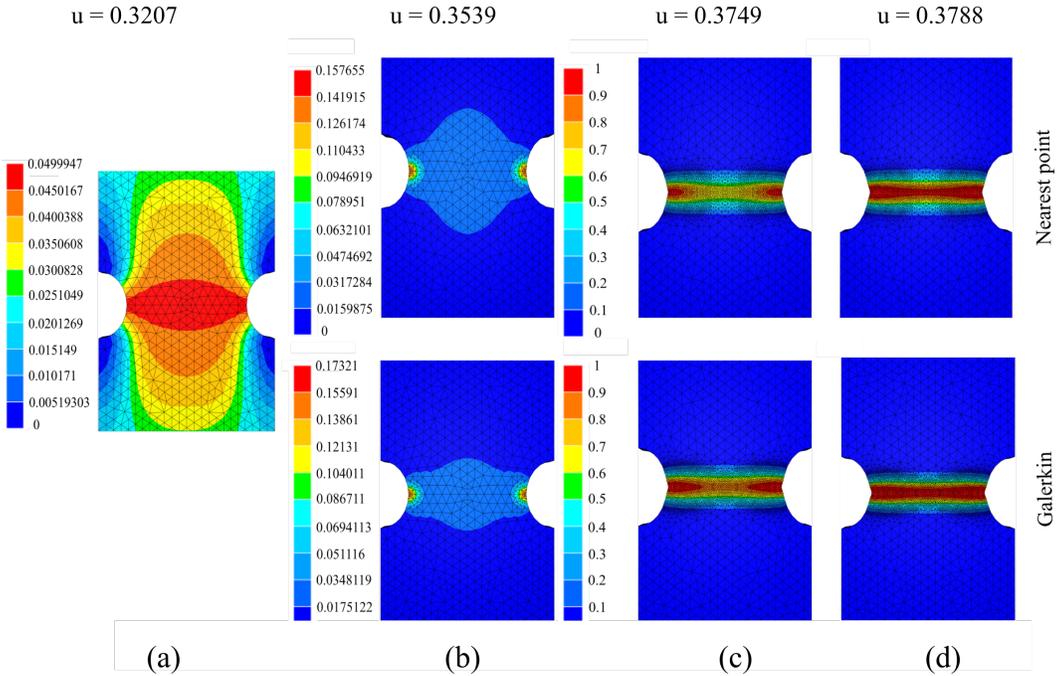


Figure 11: Evolution of phase field at different deformation states on the deformed configuration for a phase field threshold is set to 0.025. The average element size of the base mesh is set to 1.25 mm. **a.** $u = 0.3027$ mm. **b.** $u = 0.3539$ mm. **c.** $u = 0.3749$ mm. **d.** $u = 0.3788$ mm.

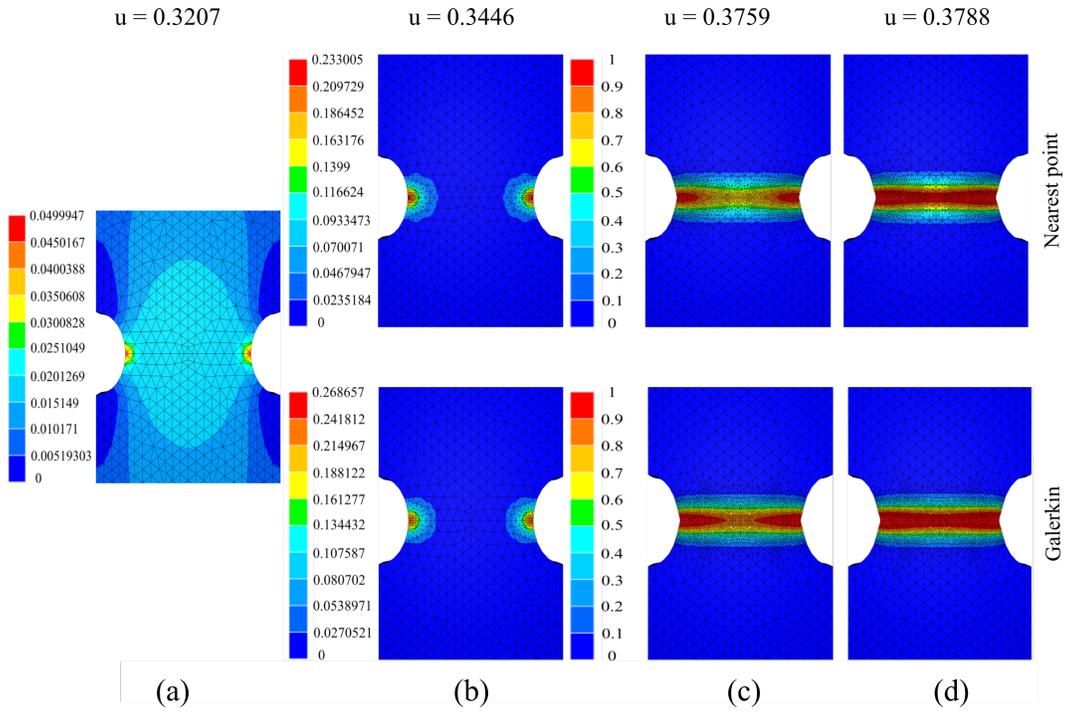


Figure 12: Evolution of phase field at different deformation states on the deformed configuration for a phase field threshold is set to 0.075. The average element size of the base mesh is set to 1.25 mm. **a.** $u = 0.3207$ mm. **b.** $u = 0.3446$ mm. **c.** $u = 0.3759$ mm. **d.** $u = 0.3788$ mm.

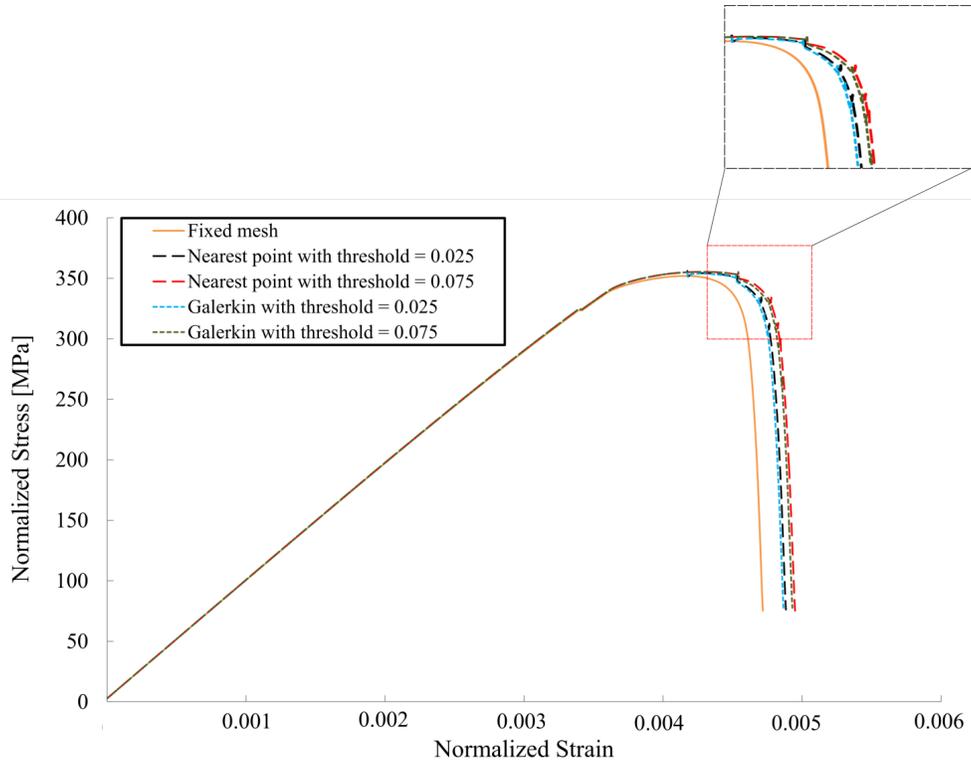


Figure 13: Normalized Stress vs. Normalized Strain curves for two different values for the phase field threshold. Comparison between the two field transfer operators with the reference case with an initial fixed mesh. The base element size = 1.25 mm.

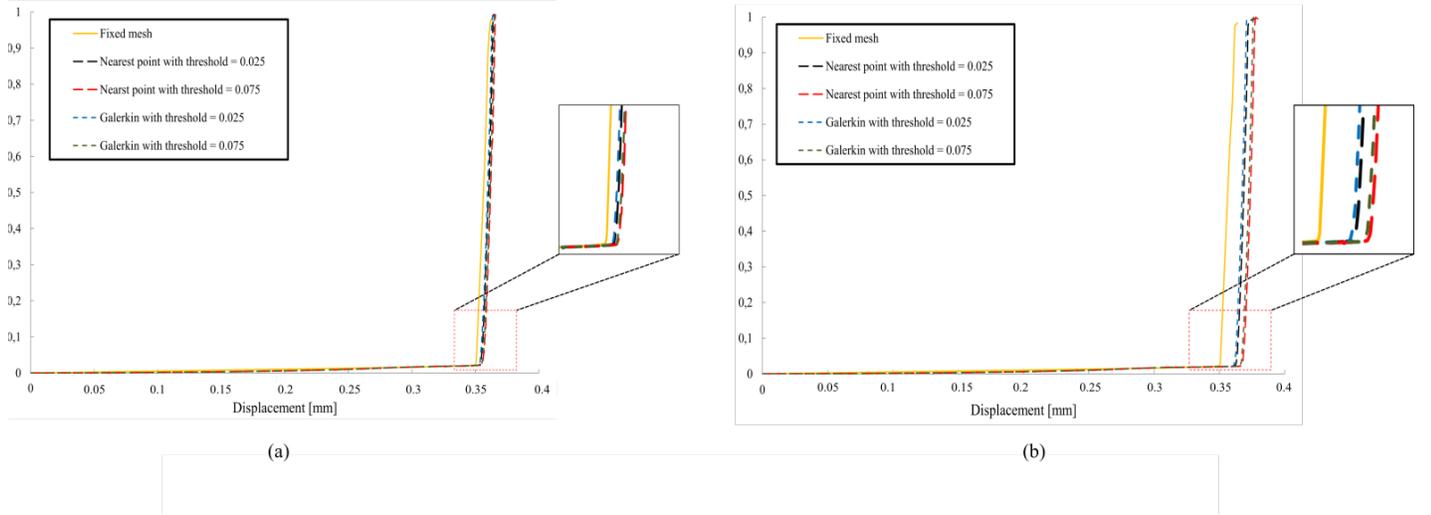


Figure 14: Comparison between the phase field evolution at a fixed mesh and with remeshing with a base element size = 0.5 mm in **a** and 1.25 mm in **b**.

Table 2: Symmetrically notched tension test with base element size = 1.25 mm.

Transfer operator	Threshold	Remeshing operations	Initial number of elements	Final number of elements	CPU run time [hour]
Fixed mesh			52278	52278	0.57
Galerkin smoothing	0.025	7	7023	43688	0.15
Galerkin smoothing	0.075	5	7023	34618	0.14
Nearest point	0.025	4	7023	38326	0.15
Nearest point	0.075	4	7023	26119	0.11

314 The conclusion here is that, it is possible to get a significant decrease of computational time
315 by using remeshing. However, the solution accuracy with remeshing is reduced when the initial
316 element size is increased. In addition, the results are improved when the phase field threshold is
317 reduced since the localization of plastic strain is well captured with the small element size, but
318 the computational time is increased. In consequence, the developed computational framework
319 can be adopted to have a good compromise between solution accuracy and computational time.
320 Regarding the field transfer operators, the results show that the data diffusion is very similar for
321 the two cases with a slight improvement exists when the Galerkin smoothing method is used. In
322 the following example, the Galerkin smoothing method is adopted for all cases.

323 4.3. Double notched specimen

324 In this example, a double notched thin specimen is used to prove the ability of the developed
325 algorithm to deal with complex crack paths efficiently. The geometry and boundary conditions of
326 the specimen are shown in Fig. 15 [17] along with the mesh size distribution. The thickness of
327 the specimen is chosen to be 0.2 mm. A quasi static loading is assumed, i.e., inertial effects are
328 neglected. The material parameters are: $E = 180$ GPa, $\nu = 0.28$, $\sigma_y = 443$ MPa, $H = 300$ MPa.

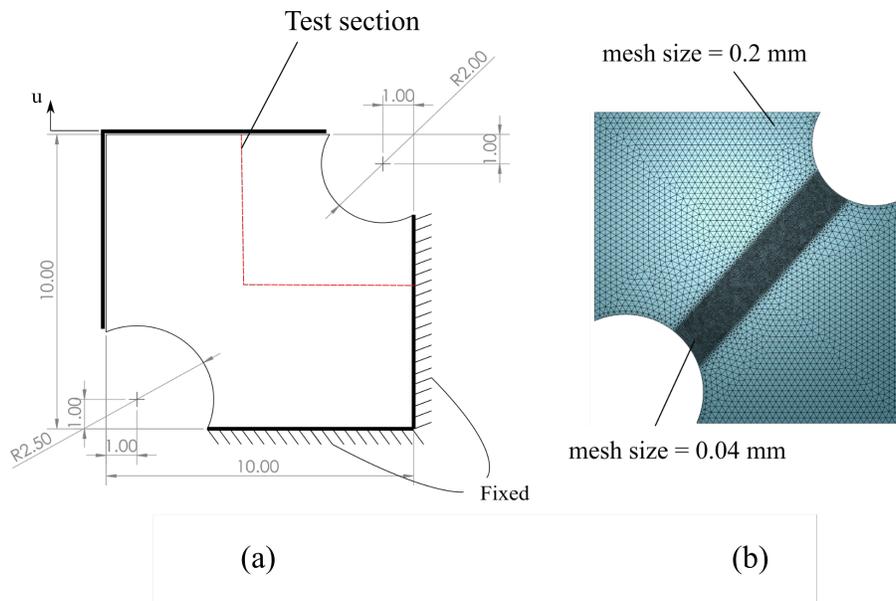


Figure 15: a. Geometry and boundary conditions of a double notched specimen. b The mesh size of the reference case without remeshing. The thickness of the specimen is 0.2 mm. All dimensions are in mm.

329 The model parameters are: $W_0 = 80$ MPa, $\beta_1 = \beta_2 = 1$, $l_c = 0.04$ mm, $G_c = 20$ kJ/m² and
 330 $\zeta = 10^{-3}$. The Galerkin smoothing method is used for all simulations in this section.

331 Fig. 16 shows the phase field evolution for a base element size of 0.2 mm where the phase field
 332 threshold is chosen to be 0.06. It should be noted that the choice of the numerical parameter η is
 333 tailored manually in all the following examples in order to obtain a similar number of remeshing
 334 operations i.e., the effect of data diffusion due to remeshing is eliminated. The loading velocity
 335 is set to 0.05 mm/sec. The time step is set to 0.01 sec in the first 200 steps since the level of
 336 the damage is still low and 0.002 for the rest of simulations in order to properly track the crack
 337 evolution.

338 The obtained phase field profile for this case indicates that the crack is initiated at the two
 339 notches which is the same observation as the reference case with a fixed mesh (this is the case
 340 which we consider as the most accurate). Then, the two crack branches propagate toward the
 341 center until merging and leading to the final failure. It can also be observed that the evolution
 342 of the refined zone in the mesh follows the phase field evolution starting from the crack initiation
 343 until the complete failure.

344 Fig. 17 shows the crack and mesh topology evolution with a base element size of 0.15 mm.
 345 The obtained cracking sequence is very similar to the case of a 0.2 mm mesh presented earlier.
 346 However, the specimen is completely fractured at a lower displacement as compared to the case of
 347 a 0.2 mm mesh size.

348 Fig. 18 shows the phase field and mesh topology evolution with a remeshing indicator function
 349 that is based on the equivalent plastic strain with a threshold value equals to 0.06. The initial
 350 element size is 0.2 mm. Remeshing is initiated at an early stage in which the zone where the crack
 351 is expected to propagate is fully remeshed before the crack initiation, i.e., the maximum value of
 352 the phase field is not yet equal to 1. It can be also observed that the refined zone is wider than the
 353 cases where the phase field is used as an indicator function. This observation is confirmed with the
 354 final number of elements in this case which is reported in table 3 as compared to the case where a
 355 phase field remeshing indicator function is used with the same initial element size.

356 Fig. 19 shows the evolution of the equivalent plastic strain at two different displacements where

357 three remeshing indicator functions are used: phase field, equivalent plastic strain and normalized
 358 yielding functions. It can be observed that the error of the equivalent plastic strain with respect
 359 to the reference case is reduced when a plastic strain threshold is used. This can be related to the
 360 fact that when the mesh size is reduced earlier, more accurate calculation of the equivalent plastic
 361 strain is obtained since the strain localization is properly captured; hence the phase field evolution
 362 becomes more accurate.

363

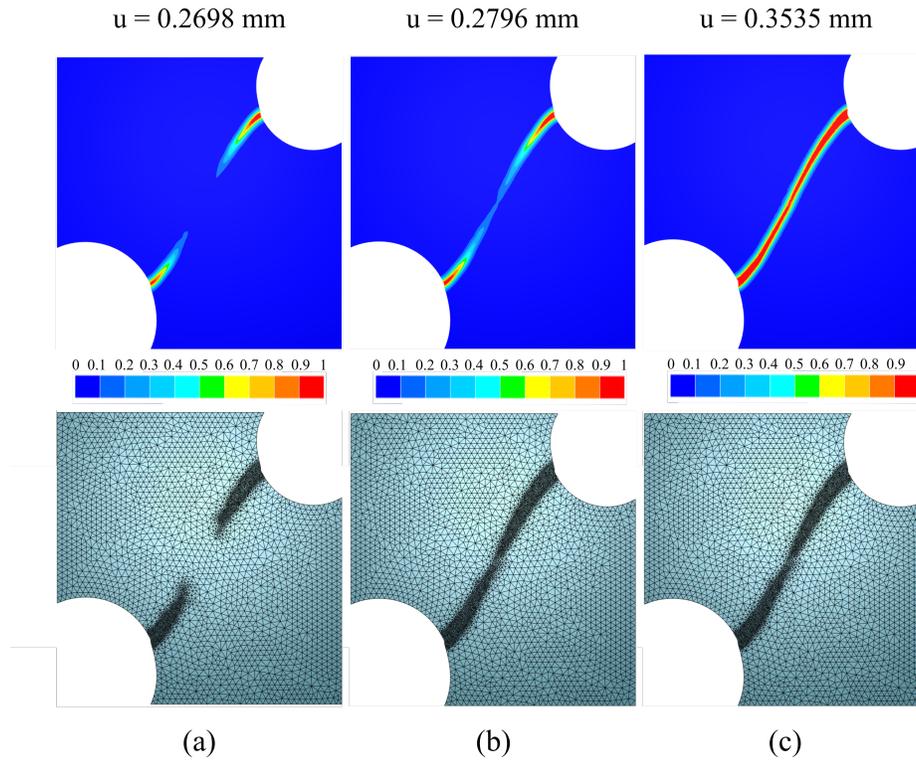


Figure 16: Phase field evolution at various deformation stages on the deformed configuration for a fine mesh with base element size 0.2 mm. The phase field is used to trigger the remeshing with a threshold of 0.06. The mesh topology is shown at each stage. **a.** $u = 0.2698$ mm. **b.** $u = 0.2796$ mm. **c.** $u = 0.3535$ mm.

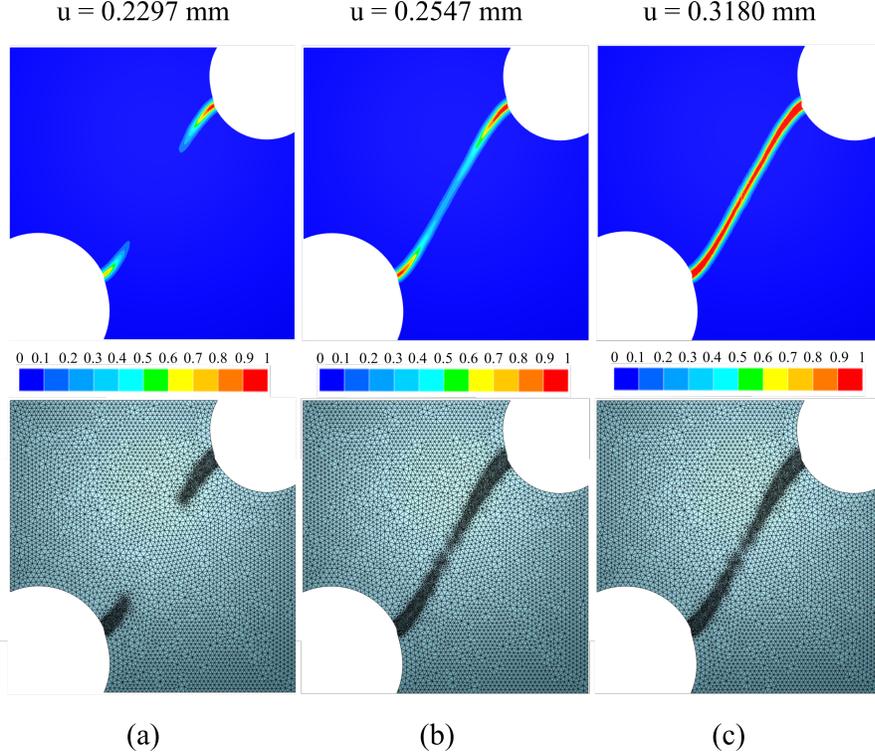


Figure 17: Phase field evolution at various deformation stages on the deformed configuration with base element size 0.15 mm. The phase field is used to trigger the remeshing with a threshold of 0.06. The mesh topology is shown at each stage. **a.** $u = 0.2297$ mm. **b.** $u = 0.2547$ mm. **c.** $u = 0.3180$ mm.

The normalized yielding function NYF defined in equation 21 is used as another remeshing indicator function.

$$NYF = \frac{f^{trial}}{\sigma_{VM}(\mathbf{u}, d)} \quad (21)$$

with this indicator function, the number of elements is reduced over time since the stress far from the crack lips (damaged region) is degraded due to the creation of the crack surface as shown in Fig 20.

The Force vs. Displacement curves are shown in Fig. 21 and. Comparing the results when remeshing is used for two mesh sizes with the reference case shows that the initial element size plays an important role in determining the moment at which the softening phase begins. Furthermore, when the mesh adaptation is based on the phase field variable, the element size in the region of interest will be only modified when the plastic energy exceeds the threshold W_0 , i.e., the phase field evolution is mainly governed by the plastic strains. The values of plastic strain will not be close enough to the reference case as to accurately contribute to the phase field evolution, hence the crack initiation is delayed. So, it seems convenient in such case to adapt the mesh based on the plastic strain or yielding function rather than the phase field variable so that the evolution of plastic strains becomes more conservative.

Table 3 shows the performance analysis for different cases along with the fixed mesh case. It can be seen that a reduction of the equivalent plastic strain threshold to 0.001 leads to results very close to the reference case with a fixed mesh at a computational cost reduced by a about 12%. In addition, when the normalized yielding function is used, the computational time is reduced by a factor of 59 % while the results are very close to the reference case with a fixed mesh. In addition, an energy error is found in the same table for each threshold type. The energy error is calculated

as follows

$$\text{Energy error } \% = \frac{\int_0^{r_{max}} (F_{remesh} - F_{ref}) dr}{\int_0^{r_{max}} F_{ref} dr} \quad (22)$$

364 where F_{remesh} is the force obtained with remeshing, F_{ref} is the force obtained from the reference
 365 case with a fixed mesh, r is the displacement and r_{max} is the maximum displacement. The energy
 366 error helps in quantifying the energy loss for each method. It can be seen that the normalized
 367 yielding function gives the lowest possible energy loss among the others which proves its accuracy.
 368

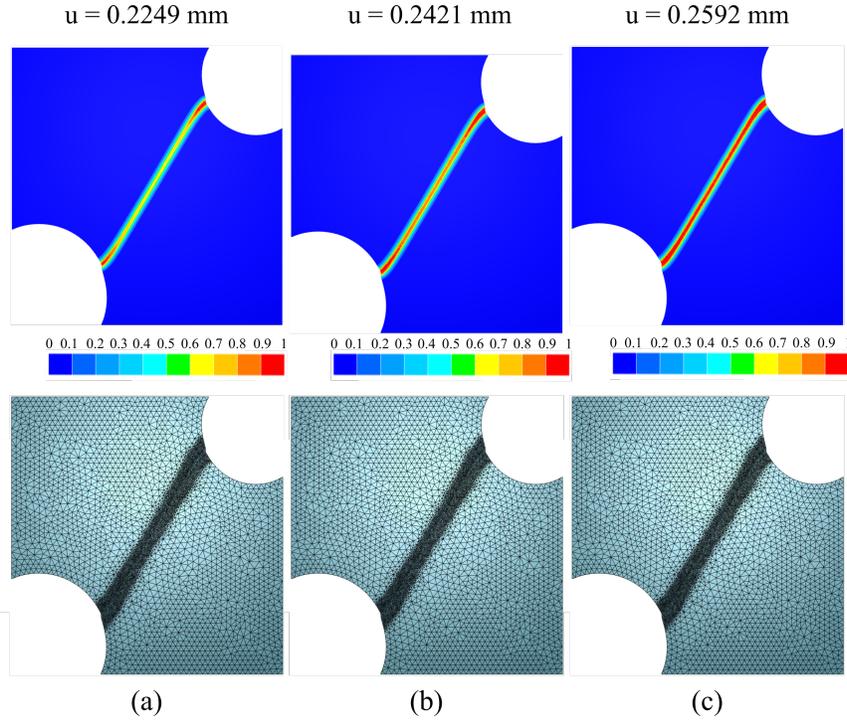


Figure 18: Phase field evolution at various deformation stages on the deformed configuration with base element size 0.2 mm. The equivalent plastic strain is used to trigger the remeshing with a threshold of 0.06. The mesh topology is shown at each stage. **a.** $u = 0.2249$ mm. **b.** $u = 0.2421$ mm. **c.** $u = 0.2592$ mm.

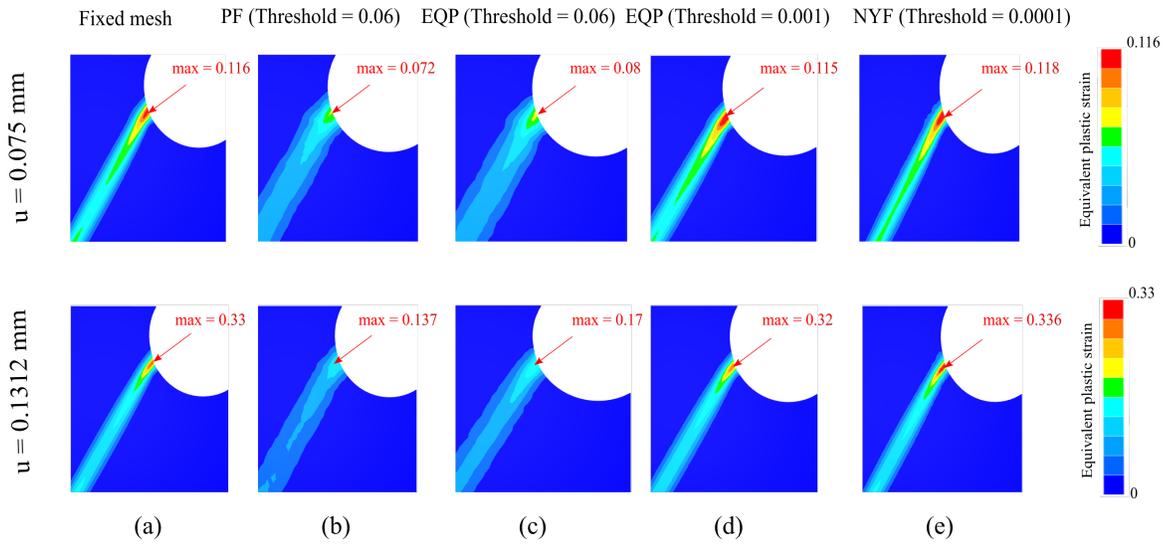


Figure 19: Evolution of equivalent plastic strain at two different displacements. Comparison is carried out between the reference case with no remeshing, remeshing with phase field (PF) threshold, two equivalent plastic strain thresholds (EQP) and normalized yielding function (NYF).

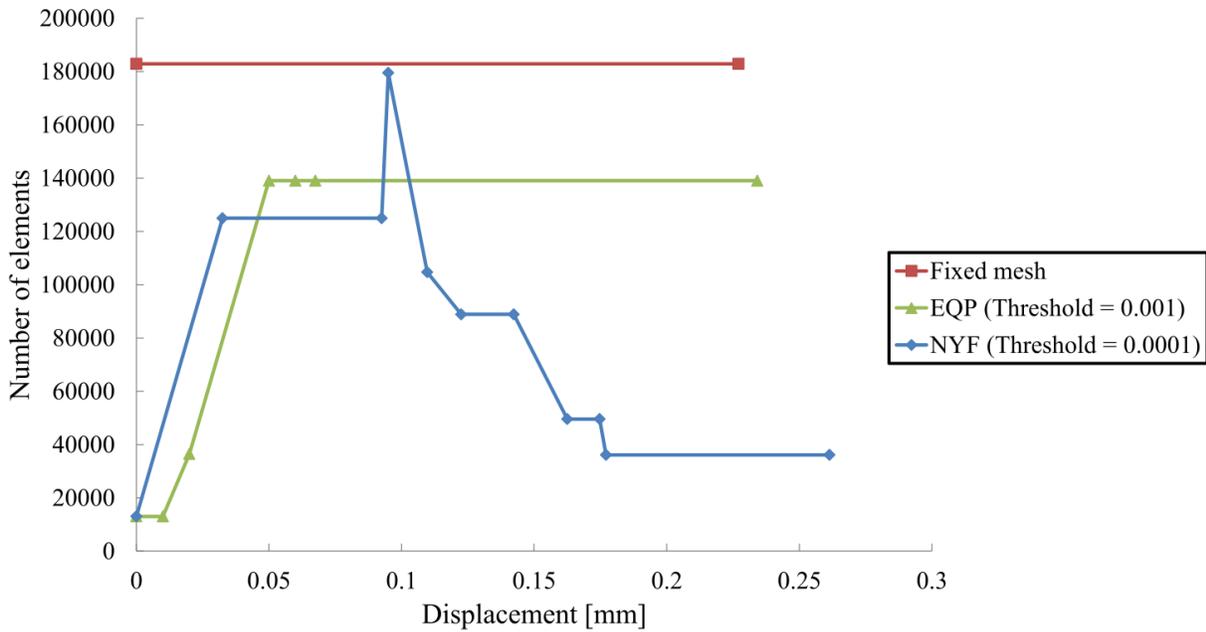


Figure 20: Evolution of number of elements for different remeshing cases along with the reference case (Fixed mesh).

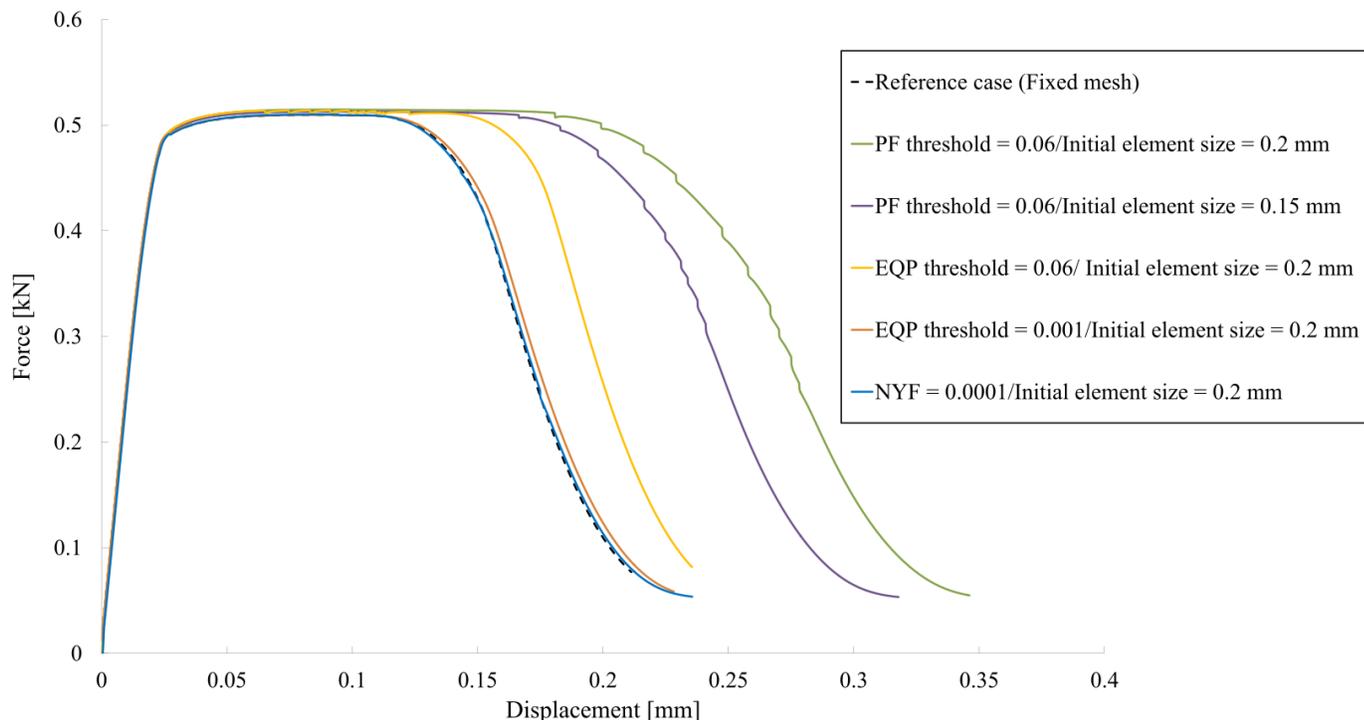


Figure 21: Force vs. Displacement curves for different remeshing cases along with the reference case (Fixed mesh). *NYF* is the normalized trial yield function.

Table 3: Double notched specimen performance analysis

Threshold	η	Threshold value	Base element size [mm]	Initial nb. of elements	Final nb. of elements	CPU time [hour]	Energy error %
Fixed mesh				182900	182900	2.25	
PF	1	0.06	0.15	23663	48193	0.8	50.7
PF	0.8	0.06	0.2	13046	41904	0.7	54.86
EQP	0.8	0.06	0.2	13046	70677	1.05	20
EQP	0.8	0.001	0.2	13046	148300	1.97	4.9
NYF	1.25	0.0001	0.2	13046	36113	0.93	2.7

369 To conclude, the proposed adaptive remeshing strategy provides a flexible compromise between
370 accuracy and computational cost. Depending on the application, whether the phase field or the
371 equivalent plastic strain can be used to trigger remeshing. When the normalized yielding function
372 is used, the obtained results are very close to the reference case with a significant reduction in the
373 computation time; hence this criterion seems to be the most suitable to be used.

374 5. Conclusion and perspectives

375 The main advantage of the phase field model is the ability to model fracture processes without
376 any special treatment for the crack initiation and propagation. In order to enhance the efficiency

377 of the computational model, an adaptive isotropic remeshing strategy is coupled with a phase
378 field model of ductile fracture. The proposed strategy offers a robust tool for predicting initiation
379 and propagation of complex crack path in highly ductile materials. This paper analysed both
380 qualitatively and quantitatively two applications with different levels of complexity: a straight
381 crack path between two notches having the same sizes and a diagonal crack formed in a non
382 symmetric notched specimen.

383 Two different field transfer operators are used in order to efficiently remap the mechanical
384 fields: (i). the nearest point interpolation; (ii). the Galerkin smoothing method. The former is
385 considered as the simplest approach since a direct interpolation is done for each integration point,
386 however its accuracy is dependent on the size of mesh and the gradient of remapped field. While
387 the latter is more computationally expensive since a smoothing step is needed to transform the P0
388 field to a P1 field. The results presented in this paper show some differences using both mapping
389 techniques. However, a lower amount of data diffusion is usually obtained using the Galerkin
390 smoothing method.

391 In order to minimize the data loss in the transfer process, two different thresholds were used: (i).
392 a remeshing indicator function threshold that is used to locate the regions where the mesh should
393 be refined; (ii). a volume quality threshold that controls the number of remeshing operations so
394 that the data loss is minimized and the numerical strategy becomes more conservative.

395 A comparison is carried out between the results when a phase field, equivalent plastic strain
396 and normalized yielding stress indicator functions are used. Results have shown that in some
397 cases where the contribution of the plastic strain in the phase field evolution is delayed, the
398 mesh in the damaged region will be refined lately; hence the evolution of the plastic strain will
399 not be accurate. On the other hand, when both the equivalent plastic strain and normalized
400 yielding functions are used to trigger the remeshing, the mesh will be refined at an early stage,
401 so the evolution of the plastic strain will be conservative for an accurate prediction for the crack
402 initiation and propagation. Unfortunately, when the equivalent plastic strain is used, the remeshed
403 region becomes wider with higher number of elements; hence the computation time is increased as
404 shown in the performance tables for all the examples. On the other hand, when the normalized
405 yielding function is used, the final number of elements is decreased due to the localization of plastic
406 strains around the damaged region. The recorded CPU times vary with each threshold depending
407 on the threshold type and value, but it can be seen that the normalized yielding function gives
408 the best possible precision with respect to the reference case with a fixed mesh with the lowest
409 computational time.

410 Several extensions are possible in the future to the developed framework. For example, testing
411 the ability of the model to predict complex fracture modes in metal forming applications for which
412 crack paths are not known a priori. In such applications, the plastic strains are very large and
413 special treatment of the crack driving force is needed to include the effect of stress triaxiality. An
414 adaptive time scheme would also be interesting in order to obtain the most efficient solution from
415 the computational point of view when combined with mesh adaptivity.

416 Appendices

417 A. Weak formulation of the problem

418 In this section, the weak form of the phase field for ductile fracture and mechanical equations is
 419 demonstrated within the framework of mixed velocity/pressure formulation. The strong form of
 420 mechanical equations is written as

$$\left\{ \begin{array}{l} \rho \frac{\partial \vec{v}}{\partial t} = \vec{\nabla} \cdot \mathbf{s} - \vec{\nabla} p + \rho \vec{g} \text{ (Conservation of linear momentum)} \\ \vec{\nabla} \cdot \vec{v} = -\frac{\dot{p}}{\kappa} \text{ (Conservation of mass)} \\ \vec{v} = \vec{v}_0 \text{ on } \partial\Omega_v \text{ (Dirichlet boundary condition)} \\ \vec{t} = \vec{t}_0 \text{ on } \partial\Omega_t \text{ (Neumann boundary condition)} \end{array} \right. \quad \begin{array}{l} (23a) \\ (23b) \\ (23c) \\ (23d) \end{array}$$

$$\partial\Omega_h = \partial\Omega_v \cup \partial\Omega_t$$

where \mathbf{s} is the deviatoric part of the Cauchy stress tensor, p is the pressure, \vec{v} is the velocity vector, κ is the bulk's modulus, ρ is the material density and \vec{g} is the body force vector per unit mass. The boundary conditions are illustrated in Fig. 1. Ω_h is the solid domain in the current configuration, $\partial\Omega_v$ and $\partial\Omega_t$ are the predefined boundaries for Dirichlet and Neumann boundary conditions, respectively. The finite element method is used to solve the system of equations 5 and 23. Following the standard Galerkin formulation by multiplying the strong form of partial differential equations by the appropriate test functions leads to the weak form of the following problem:

Find $(\vec{v}_h, p_h \text{ and } d_h) \in \mathcal{V}_h \otimes \mathcal{P}_h \otimes \mathcal{D}_h$

$$\left\{ \int_{\Omega_h} \left(\rho \frac{\partial \vec{v}_h}{\partial t} \cdot \vec{v}_h^* + \mathbf{s}(\vec{v}_h) : \dot{\boldsymbol{\epsilon}}(\vec{v}_h^*) - p_h \vec{\nabla} \cdot \vec{v}_h^* - \rho \vec{g} \cdot \vec{v}_h^* \right) d\Omega_h = \int_{\partial\Omega_t} \vec{t}_0 \cdot \vec{v}_h^* d\partial\Omega_h \right. \quad (24a)$$

$$\left\{ \int_{\Omega_h} p_h^* \vec{\nabla} \cdot \vec{v}_h + \frac{p_h^* \dot{p}_h}{\kappa} d\Omega_h = 0 \right. \quad (24b)$$

$$\left\{ \int_{\Omega_h} \frac{G_c}{l_c} d_h^* d_h + \int_{\Omega_h} G_c l_c \nabla d_h^* \cdot \nabla d_h d\Omega_h - \int_{\Omega_h} d_h^* \mathcal{H} d\Omega_h = 0 \right. \quad (24c)$$

$$\left\{ \forall \vec{v}_h^*, p_h^*, d_h^* \in \mathcal{V}_h^0 \otimes \mathcal{P}_h^0 \otimes \mathcal{D}_h^0 \right. \quad (24d)$$

$$\mathcal{V}_h = \left\{ v_h \in (H^1)^{\dim(\Omega_h)}, \vec{v}_h = \vec{v}_0 \text{ on } \partial\Omega_e, \forall e \in N_e \right\}$$

$$\mathcal{P}_h = \left\{ p_h \in (C^0)^{\dim(\Omega_e)} \cap L^2, p_h \in P^1 \text{ in } \Omega_e, p_h = p_0 \text{ on } \partial\Omega_e, \forall e \in N_e \right\}$$

$$\mathcal{D}_h = \left\{ d_h^* \in (C^0)^{\dim(\Omega_h)} \cap H^1, d_h \in P^1 \text{ in } \Omega_e, d_h = d_0 \text{ on } \partial\Omega_e, \forall e \in N_e \right\}$$

$$\mathcal{V}_h^0 = \left\{ v_h^* \in \mathcal{V}_h, \vec{v}_h^* = 0 \text{ on } \partial\Omega_e, \forall e \in N_e \right\}$$

$$\mathcal{P}_h^0 = \left\{ p_h^* \in \mathcal{P}_h, p_h^* = 0 \text{ on } \partial\Omega_e, \forall e \in N_e \right\}$$

$$\mathcal{D}_h^0 = \left\{ d_h^* \in \mathcal{D}_h, d_h^* = 0 \text{ on } \partial\Omega_e, \forall e \in N_e \right\}$$

the test functions are chosen to be the variations of the unknown variables so that the kinematic admissibility conditions are satisfied at the boundaries. Ω_h is the volume of a finite element mesh at the current configuration so that

$$\Omega_h = \bigcup_e \Omega_e (e \in N_e)$$

421 where N_e is the number of elements in the mesh.

422 A.1. Finite element model

In order to ensure the well-posedness and stability of the numerical solution, a bubble function is introduced to enrich the velocity field. The bubble function should have a value of 1 at the center of the element and vanishes at the boundaries, the resulting velocity, pressure and phase fields of the elements in the mesh can be expressed as

$$\vec{v}_h = \vec{v}_l + \vec{v}_b = \sum_{k=1}^{N_n} N_l^k \vec{v}_l^k + \sum_{j=1}^{N_e} N_b^j \vec{v}_b^j \quad (25a)$$

$$p_h = \sum_{k=1}^{N_n} N_l^k P^k \quad (25b)$$

$$d_h = \sum_{k=1}^{N_n} N_l^k d^k \quad (25c)$$

where N_l^k and N_b^k are the base and bubble interpolation functions associated with node k , respectively. N_e and N_n are the number of elements and nodes respectively. The resulting system of equations can be written as

$$\left\{ \int_{\Omega_h} \rho \frac{\partial \vec{v}_l}{\partial t} \cdot \vec{v}_l^* + \mathbf{s}(\vec{v}_l) : \dot{\boldsymbol{\epsilon}}(\vec{v}_l^*) - p_h \vec{\nabla} \cdot \vec{v}_l^* - \rho \vec{g} \cdot \vec{v}_l^* d\Omega_h = \int_{\partial\Omega_t} \vec{t}_0 \cdot \vec{v}_l^* d\Omega_h \quad (26a) \right.$$

$$\left. \int_{\Omega_h} \rho \frac{\partial \vec{v}_b}{\partial t} \cdot \vec{v}_b^* + \mathbf{s}(\vec{v}_b) : \dot{\boldsymbol{\epsilon}}(\vec{v}_b^*) - p_h \vec{\nabla} \cdot \vec{v}_b^* d\Omega_h = \int_{\Omega_h} \rho \vec{g} \cdot \vec{v}_b^* d\Omega_h \quad (26b) \right.$$

$$\left. \int_{\Omega_h} p_h^* \vec{\nabla} \cdot (\vec{v}_l + \vec{v}_b) + \frac{p_h^* \dot{p}_h}{\kappa} d\Omega_h = 0 \quad (26c) \right.$$

$$\left. \int_{\Omega_h} \frac{G_c}{l_c} d_h^* d_h d\Omega_h + \int_{\Omega_h} G_c l_c \frac{\partial d_h}{\partial \vec{x}} \cdot \frac{\partial d_h^*}{\partial \vec{x}} d\Omega_h - \int_{\Omega_h} d_h^* \mathcal{H} d\Omega_h = 0 \quad (26d) \right.$$

$$\mathcal{L}_l^0 = \left\{ \vec{v}_l^* \in (\mathcal{C}^0)^{\dim(\Omega_e)} \cap \mathcal{V}_l^0, \vec{v}_l^* \in P^1 \text{ in } \Omega_e, \vec{v}_l^* = 0 \text{ on } \partial\Omega_e, \forall e \in N_e \right\}$$

$$\mathcal{L}_b^0 = \left\{ \vec{v}_b^* \in (\mathcal{C}^0)^{\dim(\Omega_h)}, \vec{v}_b^* \in P^1 \text{ in } \Omega_e, \vec{v}_b^* = 0 \text{ on } \partial\Omega_e, \forall e \in N_e \right\}$$

with the following properties taken into account: $\int_{\partial\Omega_t} \vec{t}_0 \cdot \vec{v}_l^* d\Omega_h = 0$ since the bubble function vanishes at the boundaries, the inertial contribution of the bubble part is neglected so that $\int_{\Omega_h} \rho \frac{\partial \vec{v}_l}{\partial t} \cdot \vec{v}_b^* d\Omega_h = \int_{\Omega_h} \rho \frac{\partial \vec{v}_b}{\partial t} \cdot \vec{v}_l^* d\Omega_h = 0$ and $\int_{\Omega_h} \mathbf{s}(\vec{v}_b) : \dot{\boldsymbol{\epsilon}}(\vec{v}_l^*) d\Omega_h = \int_{\Omega_h} \mathbf{s}(\vec{v}_l) : \dot{\boldsymbol{\epsilon}}(\vec{v}_b^*) d\Omega_h = 0$ due to the

orthogonality property of the bubble and nodal spaces. The time derivative of the velocity is approximated as follows

$$\frac{\partial \vec{v}_{l,b}}{\partial t} = \frac{\vec{v}_{l,b}^{t+\Delta t} - \vec{v}_{l,b}^t}{\Delta t}$$

where Δt is the time step. Substituting equations 25 and A.1 in A.2, the final form of the residual equations can be written on the following form:

$$\mathbf{R}^{ll} + \mathbf{R}^{lp} = \mathbf{0} \quad (27a)$$

$$\mathbf{R}^{bb} + \mathbf{R}^{bp} = \mathbf{0} \quad (27b)$$

$$\mathbf{R}^{pl} + \mathbf{R}^{pb} + \mathbf{R}^{pp} = \mathbf{0} \quad (27c)$$

$$\mathbf{R}^{dd} + \mathbf{R}^{dl} = \mathbf{0} \quad (27d)$$

where \mathbf{R}^{xy} is the residual force vector of coupled set of unknowns x and y . The system of equations in 27 will be solved in a staggered manner. A Newton Raphson nonlinear solver is used to solve the system of the first three equations before each remeshing step. Then, the fourth equation will be solved independently. It is worth noting that the system of equations 27a, 27b and 27c are condensated so that the final unknowns become the velocities and pressures at the nodes without the need to explicitly solving for the bubble velocities.

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