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Centrifuge modelling of the influence of slope height on the seismic performance of rooted slopes --Manuscript Draft--

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Centrifuge modelling of the influence of slope height on the seismic performance of rooted slopes

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ABSTRACT

This paper presents an investigation into the influence of slope height on the role of vegetation to improve seismic slope stability. Dynamic centrifuge modelling was used to test six slope models with identical soil properties and model slope geometry within different centrifugal acceleration fields (10-g and 30-g, respectively) representing 1:10 and 1:30 scale slopes, i.e. slopes of different height at prototype scale. A 3-D root cluster analogue representing a tap-root system, with root area ratio (RAR), root distribution and root length representative of a 1:10 and 1:30 scale tree root cluster (of rooting depth 1.5 m at prototype scale) was modelled using 3-D printing techniques. A sequence of earthquake ground motions was applied to each model. The influences of filtering out low frequency components of the earthquake motion, such as was necessitated at the lowest scaling factor due to the practical limitations of the earthquake simulator, on dynamic amplification of motions within the slopes and the seismically induced slip, were firstly revealed. Subsequently, the effects of slope height on acceleration and deformation response of vegetated slopes were illustrated. It was found that the beneficial effects of roots on improving the seismic performance varied with the height of the slope. As an individual engineering technique for slope stabilisation, root reinforcement will not be such an effective solution for taller slopes and complementary hard engineering methods (e.g. piles, retaining walls) will be necessary. But for slopes of smaller heights (e.g. low height embankments along transport infrastructure), vegetation appears to represent a highly effective method of reducing seismic slip.

KEYWORDS: centrifuge modelling; dynamics; earthquakes; slopes; vegetation

INTRODUCTION

Previous experimental and analytical studies have led to a good understanding of root-soil interaction during soil slippage in the past 40 years (e.g Wu, 1976; Pollen and Simon, 2005; Wu, 2013). However, in contrast with this, relatively few studies have been performed on the global performance of vegetated slopes (Sonnenberg et al., 2011). Studies have generally explored reinforcement by vegetation in one of three ways. Plane-strain numerical models are most common, either through simulating the rooted zone as a soil-like continuum with additional apparent cohesion c'_r (e.g. Frydman & Operstein, 2001; Mao et al., 2014), or through treating roots as straight beams or anchor elements embedded into the continuum elements of the slope (e.g. Genet et al., 2008; Lin et al., 2010). However, as indicated by Stokes et al. (2014), such models are often not able to accurately predict the likelihood of landsliding as they are often based on oversimplified soil models and slope geometry and overlook spatial heterogeneity of the root reinforcement effect and the 3-D root group geometry. Large trials in the field

1 can overcome such disadvantages and provide a reliable insight into global slope behaviour (e.g. Brown, 1991;
2 Smethurst et al., 2006; Smethurst et al., 2012; Smethurst et al., 2015). However, such trials are generally
3 expensive and time consuming – as an example, it took 5 years to monitor the impacts of tree removal on a clay
4 railway embankment as reported by Smethurst et al. (2015). Geotechnical centrifuge modelling can provide a
5 balance between keeping expense low while maintaining a high level of fidelity and is therefore a good method
6 for investigating the global performance of vegetated slopes.

7 During centrifuge model tests, roots have previously been modelled either using live plants (e.g.
8 Sonnenberg et al., 2010; Askarinejad and Springman, 2015; Ng *et al.*, 2016) or root analogues with simple
9 geometry (e.g. Sonnenberg et al., 2011; Eab et al., 2014; Liang et al., 2015). Real plants can potentially model
10 both root mechanical and some hydrological effects, but are also highly variable, generally non-repeatable and
11 can develop very different root morphology compared to field conditions (Ghestem et al., 2013). Root analogues
12 have the advantage of high repeatability and are easily and quickly produced. The main issue with using such
13 analogues is to find a material which simultaneously models the stiffness and strength of live roots (Liang et al.,
14 2014). Liang et al. (2015) and Meijer et al. (2016) employed 3-D printed ABS plastic to fabricate root analogues
15 with simplified geometry (namely, straight vertical or horizontal rods), and this approach provided substantially
16 more representative properties compared to previously used analogue materials such as wood and rubber. Plate/
17 heart root systems of shrubs and trees, in which most of the roots behave independently, may be simplified into
18 straight root groups (Stokes and Mattheck, 1996; Gary and Sotir, 1996; Liang et al., 2015). However, for deep
19 tap root systems, for which the main tap root penetrates into the soil to significant depth and mobilises other
20 attached roots to resist soil movement, it will not be appropriate to model them as straight root groups (Danjon
21 et al., 2013). A more sophisticated root model which can simulate realistic geometry of a deep tap root system
22 is required, and 3-D printing offers an opportunity to achieve this.

23 Most previous studies have been concerned with studying failure under changes to the hydraulic conditions
24 within the ground (e.g. Sonnenberg et al., 2010; Sonnenberg et al., 2011; Ng et al., 2016; Eab et al., 2014;
25 Askarinejad and Springman, 2015). However Liang et al. (2015), for the first time, investigated the global
26 behaviour of vegetated slopes subject to a sequence of earthquake ground motions, using straight root analogues
27 as described above. The 1.5 m deep vegetation layer modelled appeared to act as a soft retaining wall,
28 buttressing the movement of the slipping soil mass and significantly decreasing permanent settlement at the
29 crest for the case of a 2.4 m high slope at prototype scale. For taller slopes having vegetation of a similar depth,
30 it is unclear whether such a mechanism will still be active, or whether the failure mechanism may bypass the
31 rooted zone.

32 To address the above issues, this paper discusses the results of a programme of dynamic centrifuge
33 testing with the same model slope geometry (1:2 slope in sand) but performed at different scaling factors (1:10
34 and 1:30) and corresponding centrifugal acceleration fields (10-g and 30-g, respectively) subjected to a sequence
35 of earthquake ground motions. The tests include both vegetated cases (using analogues, see below) and fallow
36 benchmarks and all the vegetated cases have nominally the same rooted layer properties and geometry (1.5 m
37 deep) at prototype scale. 3-D model root clusters with root area ratio (RAR), root distribution and root length
38 representative of 1:10 and 1:30 geometrically-scaled models of the same tap-root system of a tree, were
39 developed using 3-D printing techniques. The use of different scaling factors for representing different height

1 slope prototypes has implications for earthquake motion replication as the scaling factor for frequency, coupled
2 with mechanical limitations of servo-hydraulic earthquake simulators, limits the low frequency content of the
3 ground motions that can be controlled at smaller scaling factors (i.e. the 1:10 models herein). The seismic
4 response of three fallow slope models is therefore investigated first to determine the effects of the frequency
5 content of the earthquake motion on seismic ground motions and site/topographic amplification behaviour, and
6 the permanent soil slip. This provides a benchmark for subsequent assessment of the comparative performance
7 of rooted slopes of different heights, from which some recommendations for engineering practice are drawn.

9 DYNAMIC CENTRIFUGE MODELLING

10 Dynamic centrifuge modelling was conducted using the 3.5 m diameter beam centrifuge and servo-hydraulic
11 earthquake simulator at the University of Dundee. A detailed description of this equipment can be found in
12 Brennan et al. (2014). A total of 6 model slopes with identical overall geometry and soil properties were tested
13 at different g-levels and with input motions with frequency contents as indicated in Table 1. All values
14 presented herein are given at prototype scale, unless specifically noted otherwise. Typical model layouts are
15 shown in Fig.1 for models TL 07 (a) and TL 06 (b). It should be noted here that the root cluster in Fig. 1(b) is
16 shown simplified as a dotted circle for clarity.

18 *Model preparation*

19 The slope models were constructed within an Equivalent Shear Beam (ESB) container in order to replicate a
20 semi-infinite horizontal boundary condition in the direction of shaking (Zeng and Schofield, 1996; Madabhushi
21 and Teymur, 2003; Brennan et al., 2006; Haigh and Madabhushi, 2014). Further information on this specific
22 container can be found in Bertalot (2013). The slopes (at model scale) were 240 mm tall from toe to crest, and
23 were underlain by a further 80 mm of sand at the same relative density and had a slope angle of 27° (1:2). The
24 root clusters (described in the following section) were hung at the specified positions shown and dry HST 95
25 Congleton silica sand was pluviated in air around the model roots to a relative density of $I_D = 55\%-60\%$.
26 Fundamental properties of the sand are given in Table 2. Once the lower part of the root clusters was embedded
27 in the soil, the lines used to hang the root clusters were cut off and removed. In this way, the root clusters most
28 closely represented a 'wished-in-place' installation and therefore conservatively, may not represent small local
29 (positive) changes to soil density/properties in the vicinity of roots growing into the soil in a field condition.
30 ADXL78 micro-electromechanical system (MEMS) accelerometers (ACC) manufactured by Analog Devices
31 were embedded inside each model to measure the horizontal accelerations within the soil specimen, and three
32 external linear variable differential transformers (LVDTs) measuring settlement at the crest of the slope along the
33 centreline and detecting any boundary effects (Madabhushi and Teymur, 2003). All slopes were tested dry to
34 avoid the potential for the complicating effects of liquefaction. Further details on model preparation can be
35 found in Liang (2015).

37 *Model tree roots*

1 Simplified 3-D root model clusters (Fig. 2) with root area ratio (RAR), root distribution and root length
2 representative of a 1:10 and 1:30 geometrically-scaled tree root cluster consisting of a tap-root system was
3 modelled. The root architecture used as a template was based on the tap root system of a white oak tree located
4 at the Warnell School for Forestry and Natural Resources, University of Georgia, for which detailed
5 characterisation of the root system had been undertaken (as reported in Danjon et al. 2008). Further details
6 relating to the design process for this model can be found in Liang (2015). Willow, oak, poplar, beech, alder and
7 pine trees are some typical choices for the use of vegetation to stabilise slopes (Norris and Greenwood, 2006),
8 though naturally vegetated slopes may have a much wider selection of species growing on them. There are very
9 limited databases of detailed root system architecture of trees; the root system considered here grew in sloping
10 ground and was therefore considered to be a suitable example root system for this study.

11 All of the roots except the tap root were simplified into circular curved rods and classified into different
12 types (after Watson et al., 1995) based on their diameter, as shown in Table 3. The 3-D geometry can be seen in
13 Fig. 1(a). The model root clusters produced were fabricated using the Stratesys Inc. uPrint SE Acrylonitrile
14 Butadiene Styrene (ABS) rapid prototyper (known more commonly as a 3-D printer) at the University of
15 Dundee following the procedures outlined in Liang et al. (2014), which discusses the 1:10 scale model.
16 Compared with the 1:10 scale root cluster, the smallest model roots were eliminated in the 1:30 scale root
17 cluster as shown in Table 3, due to the threshold minimum manufacturing size in the 3-D printer (0.75 mm in
18 diameter). The corresponding differences in root distribution at prototype scale are shown in Fig. 3. The 3-D
19 printing technique can generate a unidirectionally layered structure, which can successfully simulate the fibrous
20 structure of tree roots. The layered ABS plastic root analogues were validated to be highly representative of the
21 mechanical behaviour of real roots (in terms of Young's Modulus and tensile strength) after a series of uniaxial
22 tension and bending tests, which is described in more detail in Liang et al. (2015).

23 The mean particle size of the sand used was 0.16 mm, while the minimum diameter of root segments
24 modelled was 0.8 mm, which is only $6.7D_{50}$. Ovesen (1979) proposed that there was some deviation from
25 continuum behaviour in centrifuge models when the ratio of foundation diameter to grain size was less than
26 approximately 15 (Stone and Wood, 1992; Kutter, 1995). To verify what the impact of potential scale effects
27 might be, a series of direct shear tests were conducted in a large direct shear apparatus (DSA, Fig. 4) with
28 internal dimension of 300 mm × 300 mm × 270 mm, purpose-built for investigation of root-soil interaction.
29 Further details about the advantage of such a large DSA compared with a conventional DSA for investigating
30 rooted soil can be found in Liang (2015). The same 3D root clusters and density of soil as used in the centrifuge
31 tests were used in the large DSA. The varied vertical confining stress for different potential slip plane locations
32 in the centrifuge test was simulated in the DSA through altering the surcharge weight and varying the vertical
33 position of the root cluster within the DSA. However, it should be noted that these tests are only indicative of
34 the rooted soil shear strength at different depths within the centrifuge models as the trend of increasing
35 confining stress with depth in the centrifuge tests could not truly be simulated, as demonstrated in Fig. 5(a). The
36 DSA tests did however verify that the additional shear strength for both 1:30 and 1:10 scale root clusters were of
37 the same order of magnitude and distribution with depth for the same applied effective stresses, as shown in Fig.
38 5(b). This suggested that there was a negligible particle size effect, despite the differences in model scale root
39 analogue diameter at the different scales compared to the fixed median soil grain size in all tests.

Earthquake events

Earthquakes were simulated in-flight using the Actidyn QS67-2 servo-hydraulic earthquake simulator (EQS). The performance of this actuator is described in Brennan et al. (2014). Each slope model was subjected to eight successive earthquake motions (see Table 4), comprised of three different recordings with distinct peak ground acceleration (PGA), duration and frequency content. The motions used were recorded during the $M_s=6.2$ Aegion earthquake in 1995 (PGA=0.39g), the $M_s=6.8$ Northridge earthquake in 1994 (PGA=0.83g) and the $M_s=6.3$ L'Aquila earthquake in 2009 (PGA=0.33g). The three motions were downloaded from the PEER (Pacific Earthquake Engineering Research) Next Generation Attenuation model database and are shown as acceleration response spectra (ARS), normalised by the peak acceleration for the case of a system with nominal 5% damping in Fig. 6. All ARS reported subsequently in this paper are given at 5% damping, unless otherwise stated.

The motions were each band-pass filtered using an eighth-order Butterworth filter to obtain demand motions (see Fig.7) which were within the controllable range (40-300 Hz at model scale) of the EQS. At 1:10 scale this range is between 4 Hz and 30 Hz at prototype scale, while at 1:30 scale this range is between 1.33 Hz and 10 Hz. As mentioned above, significant differences in the seismic performance of slopes between these two scales may be expected due to the combined effects of different slope heights at prototype scale (hence different natural frequencies in the fundamental mode) and input motion frequency. Additionally, much of the energy associated with significant slip of the slope will be at low frequency, such that the overall magnitude of the permanent deformations in the 1:10 scale models may be expected to be much smaller than the 1:30 scale models. Evidence of this effect can also be seen in the significant differences in peak input acceleration between the two scales as shown in Table 4, and compared to the 'as-recorded' PGA values reported in the previous paragraph. A 'reduced' range at 1:30 scale of 4-10 Hz was therefore also introduced to provide both 1:10 scale and 1:30 scale models with the same amount of low frequency motion (< 4 Hz) filtered out in each case, so that a comparison could be made where only the slope height was different in the fallow case. It should be noted here than the frequency ranges between those two models are still not the same, but the higher frequency components (above 10 Hz) are not expected to be important for slip of the slope.

All motions were initially calibrated on a dummy slope model identical to Fig.1, but without instrumentation before formal testing to obtain repeatable achieved motions as close as possible to the filtered demand motions.

Natural frequency of the model slopes

The natural frequency (f_0) of the model slopes was estimated using:

$$f_0 = V_s / kH \quad (1)$$

where V_s is the average shear wave velocity, H is the soil layer height (here, the slope height) and k is a coefficient for the shape of the soil layer ($k = 4$ for a semi-infinite horizontal layer; $k = 2.61$ for a triangular shaped layer, such as a slope (Gazetas, 1992)). In this study, no resonant column (RC) tests were performed, but

1 the shear wave velocity can be estimated based on the maximum shear modulus (G_0) at small strain below the
2 elastic threshold:

$$3 \quad G_0 = \rho V_s^2 \quad (2)$$

4 where ρ is the density of the soil. Given the round shape of the particles ($R= 0.53$) of the HST 95 sand used in
5 this study (Lauder, 2010), G_0 was here estimated using the relationship based on void ratio (e) proposed by
6 Hardin and Black (1966) for round-grained sand at stresses less than 96 kPa:

$$7 \quad G_0 = 7060 \frac{(2.12 - e)^2}{1 + e} \cdot (p_0')^{3/5} \quad (3)$$

8 where p_0' is the initial mean effective confining stress, which can be expressed as:

$$9 \quad p_0' = \frac{(1 + 2K_0)\sigma_v'}{3} \quad (4)$$

10 where σ_v' is the average vertical effective stress and K_0 is the earth pressure coefficient at rest, which was
11 estimated using:

$$12 \quad K_0 = 1 - \sin \phi' \quad (5)$$

13 where ϕ' is the effective angle of friction. A value of $\phi' = 32^\circ$ was reported by Al-Defae et al. (2013) for HST 95
14 sand, and was also used herein.

15 According to Eq (1)- Eq (5), the average natural frequency of the slope at 1:10 and 1:30 scale were
16 estimated to be 13.9 Hz (0.07 s period) and 6.5 Hz (0.15 s period), respectively, and these values are shown with
17 the demand motions in Fig 7.

19 SEISMIC PERFORMANCE OF FALLOW SLOPES

20 The seismic response of the fallow slopes under sequences of strong motion **will be discussed first**. This will
21 provide a benchmark to subsequently assess the comparative performance of the rooted slopes.

23 *Dynamic response – effect of frequency content of input motion*

24 Comparing the 1:30 scale fallow models at reduced frequency range (TL-08) and at ‘full’ frequency range (TL-
25 05) allows the same slope profile at prototype scale to be considered with the only difference being the amount
26 of low frequency signal content contained within the ground motion. Comparison of the seismic performance of
27 these two models was important to determine what the implications of a lack of low frequency content will be
28 on slope behaviour, as was necessitated by the scaling factor used in the 1:10 scale tests.

1 A comparison of the peak acceleration amplification factor (S_{pk} = peak acceleration at a given depth
 2 divided by the peak acceleration of the input motion in the centrifuge tests) as a function of normalised elevation
 3 (z/H) of models TL 05 and TL08 is shown in Fig.8. Here, the first motion of each type was selected (i.e. EQ1,
 4 EQ2 and EQ5). Values suggested by Eurocode 8, Part 5 (BSI 2005b) for the crest ($z/H = 1$), are also included
 5 for comparison, where:

$$S_{pk} = S \cdot S_T \quad (6)$$

7 where S is a soil factor describing the site effect. $S= 1.4$ for the 'ground type E' soil in this study, as classified
 8 using Eurocode 8, Part 1 (BSI 2005a), and S_T is a topographic amplification factor of ≥ 1.2 for shallow slopes.
 9 The overall minimum amplification factor is therefore 1.7.

10 The response in the deeper soil ($z/H < 0.2$) is very similar in each case and includes a limited amount of
 11 attenuation for EQ2 and EQ5 which have the higher peak input acceleration, as previously observed by Ha et al.
 12 (2014). Towards the crest of the slope, the reduced motions EQ1 and EQ2 present much higher amplification
 13 factors with the exception of EQ5, which shows similar magnitude between the full and reduced motions. These
 14 findings are broadly in agreement with Fig. 7, given that the full versions of EQ1 and EQ2 consist of much low
 15 frequency (1.33-4 Hz) or high period content which was removed pre-test to fit the range of earthquake
 16 simulator, while EQ5 is mainly composed of higher frequency (lower period) components, hence showing less
 17 significant changes after filtering out low frequency components. This was further identified by examining
 18 dynamic amplification in the frequency domain via a transfer function, as shown in Fig. 9. The amplification at
 19 the crest is strongly frequency-dependent as evident in Fig.9 (a). Lower frequencies, below about 3 Hz, show a
 20 consistent amplification with a magnitude of less than 1.7, while at frequencies higher than 3 Hz, the
 21 amplification is seen to diverge but generally is much higher than 1.7. Such observations are consistent with the
 22 behaviour reported by Brennan and Madabhushi (2009). Therefore, filtering out the low frequency components
 23 (1.33-4 Hz) which have a lower amplification factor will result in a higher overall amplification factor for EQ1
 24 and EQ2. Fig.10 shows a comparison of the spectral amplification factor (S_{amp} , given by dividing the crest
 25 spectral ordinates by those of input motion) between the same two models and shows that the S_{pk} values in Fig.8
 26 are correlated with the difference in S_{amp} at periods above the natural period of the slope (i.e. low frequencies).
 27 Finally, it is apparent from Fig. 8(c) and Fig. 10(c) that the narrow-banded L'Aquila motion (EQ5-EQ7) is
 28 highly suitable for use in tests where different scaling factors are applied. The same is likely to be true of other
 29 motions with only limited low frequency (high period) content.

31 *Dynamic response – effect of slope height*

32 Having ascertained the impact of the input motion frequency content on the dynamic amplification within the
 33 slope, a comparison of tests TL-04 and TL-08 allows a comparison of two 1:2 slopes of different prototype
 34 heights, namely 2.4 m and 7.2 m, respectively, in each case with the same low frequency cut-off in the input
 35 motion (4 Hz). The ground motion at the crest for model TL 08 was observed to be generally larger than that of
 36 TL-04 for the same peak acceleration of the input motion. The variation of peak acceleration amplification
 37 factor with normalised elevation for these cases is shown in Fig.11. In two out of the three motions considered

1 (EQ1 and EQ2), the taller slope shows increased amplification compared to the shorter slope, up to or beyond
2 2.5 × the input motion peak. In all cases the amplification at the crest is significantly larger than the value of 1.7
3 suggested by EC8, but closer to the value of 2.1 (refer to Eq.6, $S_T = 1.5$) as suggested by Ashford et.al (2002)
4 and Brennan and Madabhushi (2009). These observations would suggest that topographic amplification factors
5 should be substantially increased, particularly in taller slopes.

7 *Dynamic response – effect of aftershocks/preshocks*

8 Fig.12 shows the recorded S_{pk} for the first and last earthquakes of similar type in test TL05 (i.e. for the tallest
9 slope with ‘full’ frequency content). In this way it is possible to observe what the effect of previous strong
10 ground motions is on the dynamic response of the slope in a subsequent event (i.e. in a strong aftershock).
11 **Generally the dynamic response of the ground was found to be insensitive to previous shaking,** though by
12 comparing each pair of like motions, a small amount of additional amplification can be seen in the later motion
13 (e.g. compare EQ4 to EQ2 or EQ7 to EQ5). The effect is most apparent comparing EQ8 to EQ1 – these are both
14 nominally the same motion, but EQ8 occurs after a significant amount of previous strong shaking. These
15 observed small increases in amplification during later motions are presumably a result of densification of the
16 soil outside of any slipping zone during previous strong shaking. If this is true, then in practical applications any
17 effects of historical shaking may be captured through the site investigation and subsequent determination of the
18 current state of the soil.

20 *Permanent slope deformations*

21 Fig. 13(a) shows a comparison of the permanent crest settlement across the eight earthquakes for model TL-05
22 and TL-08. It is found that in contrast to the dynamic motions within the main soil body (Fig. 8) the effect of
23 **removing the low frequency content of the input motion is highly significant for the permanent settlement at the**
24 **crest.** A reduction of 60% on permanent slope settlement was observed when the low frequency content between
25 1.33 Hz and 4 Hz was removed. Considering the response in terms of a Newmark sliding block analysis
26 (Newmark, 1965), such low frequency components, having longer periods, would result in greater slip when
27 they exceed the yield acceleration of the slope compared to higher frequency components of the same peak
28 ground acceleration, due to the generation of larger slip velocities and hence, displacements. As a result, it is to
29 be expected that these components will contribute the greater part of the accumulated slip.

30 A comparison of the permanent crest settlement across the eight earthquakes for models TL-04 and TL-08
31 (i.e. different height slopes with similar low frequency content) is shown in Fig. 13(b). An increase of
32 approximately 175% on permanent slope settlement was observed when the height of the slope was increased
33 from 2.4 m to 7.2 m. This ratio is broadly consistent with the increase in peak ground accelerations near the
34 surface of the soil (the likely sliding mass) in the taller slopes (Fig.11) for the motions with significant low
35 frequency content (EQ1 and EQ2) and can again be understood via the behaviour of a Newmarkian sliding
36 system. If the two slopes, because of their identical slope angle, will both yield through the formation of a
37 mechanism close to an infinite slope, then their yield acceleration will be the same (or at least similar). However,

1 the larger size of the ground motions with longer period components will mean that yield will be exceeded more
2 often and with increased slip velocity (and hence, displacement) on each occasion, resulting in significantly
3 increased slip.

4 **The effects of preshocks and aftershocks on the deformations can also be evaluated for the full sequence of**
5 **eight earthquake motions using Fig.13.** As previously observed for similar fallow slopes by Al-Defae et al.
6 (2013), the permanent slip in subsequent nominally identical ground motions reduces due to re-grading
7 (geometric hardening through a reduction in slope angle with continued slip). This same effect can be observed
8 in Fig.13 particularly comparing EQ2-EQ4 and EQ5-EQ7.

10 SEISMIC PERFORMANCE OF ROOTED SLOPES

11 *Dynamic response*

12 A comparison of shear modulus and damping as functions of cyclic shear strain within rooted and fallow slopes
13 is shown in Fig.14. The data points were determined from second-order estimates using the accelerometer array
14 at the crest of the slope following the method proposed by Brennan et al. (2005). They therefore represent the
15 behaviour at slope mid-height. Some empirical models from the literature are also presented for comparison
16 (Hardin and Drnevich, 1972; Ishibashi and Zhang, 1993; Oztoprak and Bolton, 2013). In the taller slopes (Fig.
17 14(b) and (c)) the shear modulus and damping at a given cyclic shear strain was highly similar between rooted
18 and fallow slopes and this did not appear to be affected by the amount of low frequency content within the
19 motion (though it can be seen that there is an increase in the maximum cyclic strain magnitude in the tests with
20 greater low frequency content, TL05 and TL06). In the shorter slopes, the shear modulus appears to be reduced
21 compared to the fallow case, while the damping is significantly higher (Fig. 15(a)). These two effects would
22 tend to cancel each other out, and so the presence of the model roots in both cases would likely have a very
23 limited effect on the overall dynamic behaviour of the soil.

24 To further investigate the dynamic response, ratios of peak acceleration (i.e. rooted/fallow) at the crest and
25 locally within the rooted zone are shown in Fig. 15. A comparison of (a) and (b), where both cases have similar
26 filtering-out of the low frequency components of the motion, shows that the roots locally reduce the amplitude
27 of the dynamic ground motions in the smaller height slope (Fig. 15 (a)) while there is very little change in the
28 larger height slope (Fig. 15(b)). **Comparison of Fig. 15(b) to Fig. 15(c) suggests that there is little change locally**
29 **whether or not there is significant low frequency content for a given slope height**, as previously suggested by
30 Fig. 14. Again considering these observations within a Newmarkian framework would suggest that in **smaller**
31 **height slopes, such as the 2.4 m high slope considered herein,** the motions within the slipping mass of soil near
32 the slope surface may be attenuated, potentially reducing accumulated seismic slip, **while taller slopes (e.g. 7.2**
33 **m high slope here)** may suffer larger slippage for a given ground motion as a result of negligible attenuation.
34 This will be further discussed when discussing permanent deformations in the following section.

35 Although root systems may locally reduce acceleration magnitudes, affecting soil slip and permanent
36 deformations, it is also important to understand how the overall dynamic motion at the crest of the slope may be
37 affected by the presence of the roots, as this would represent the dynamic input that may be seen by

1 infrastructure located at the crest (e.g. if this were a transportation embankment). By examining the ‘At crest’
2 points in Fig. 15 it can be seen that in general the peak magnitude of the motion is unaffected by the presence of
3 the roots, irrespective of whether there is local attenuation close to the rooted zone.

5 *Permanent deformations*

6 Fig. 16 shows a comparison of the permanent settlement at the crest of the slope between rooted and fallow
7 cases. As observed for the fallow cases (Fig. 13), a decreasing trend of settlement was observed in the rooted
8 slopes when subjected to successive strong motions (e.g. aftershocks) attributable to the aforementioned slope
9 geometry change (re-grading). Reductions by 85% and 15% of the permanent fallow slope movement were
10 observed due to the presence of the roots, for the 1:10 scale model (Fig. 16(a)) and 1:30 scale model (Fig. 16(b)),
11 respectively. The majority of this reduction was observed in the first two motions (EQ1 and EQ2) for the 1:10
12 scale models which is consistent with previous observations of a simplified straight root analogue case
13 representative of a plate / heart type root system previously reported by Liang et al. (2015). This is attributable
14 to the rapid mobilisation of root-soil interaction due to the initial soil slip under dynamic loading. After the
15 initial rapid mobilisation, the additional resistive force of the root was largely constant and associated with
16 yielding of the soil around the roots.

17 Given that the root analogues at different scales had highly similar strengthening effects on the soil over
18 the upper 1.5 m (Fig. 5), it is perhaps surprising that the 1:30 scale rooted model experienced a much lower
19 reduction of crest settlement compared with 1:10 scale rooted model. To understand this behaviour, the
20 Newmark sliding block framework can again be considered. Within this framework, the presence of the roots
21 could feasibly reduce permanent slip in two ways: (i) by increasing the yield acceleration of the slope, either
22 through a change of soil strength or a change of failure mechanism; or (ii) via a reduction of the dynamic
23 motions within the slope (specifically near the surface in the sliding mass).

24 Fig. 15 has already provided some evidence for point (ii), namely that motions are attenuated somewhat in
25 the smaller slope, unlike in the taller slope. In terms of point (i), Fig. 6 has shown that in both cases the root
26 models add significant additional shear strength within their zone of influence, especially considering the low
27 confining stresses within the soil over the top 1.5 m. Previously Al-Defae et al. (2013) determined that the shear
28 plane in a fallow 1:2 slope formed of the same soil at the same relative density and for a similar height ($H = 8$ m,
29 compared to $H = 7.2$ m for the 1:30 slope in this study) was at a depth of approximately 0.5 m and was of the
30 translational/infinite type. Therefore it may be inferred that a translational failure will also be critical and at a
31 similar depth in the smaller fallow 1:10 slope. The roots always have a positive contribution to shear strength at
32 whatever depth the shear plane is (Fig. 5), until close to their tips, at which point the strength reverts to being
33 provided by the soil only. Therefore it is highly likely that the optimal position of the shear plane associated
34 with the critical failure mechanism over the central (majority) part of the slope will be pushed deeper, as it will
35 be easier to shear through the unreinforced soil below the root tips, rather than through the quite extensively
36 reinforced rooted zone. In the case of the 1:10 scale slope, this would result in significant changes to the
37 geometry of the slip plane around the toe of the slope to form a kinematically admissible mechanism (refer to
38 Fig. 1). Such changes to the mechanism geometry would be less severe in the case of the 1:30 slope (where the

1 root depth is only 21% of the slope height) and so it is likely that the yield acceleration of the smaller slope (root
2 depth is 63% of H sufficient to induce a buttressing mechanism, Liang et al. 2015) will be increased by more
3 than the taller slope. The cumulative effect of reduced dynamic motion and a higher yield acceleration may
4 explain why the roots are apparently much more effective at reducing slip in the shorter slope; however, such a
5 mechanism requires further investigation.

6 The centrifuge observations from this study, therefore potentially suggest that there may be a limiting
7 height of slope (or height of slope as a function of rooting depth) beyond which other, more traditional forms of
8 reducing slip (e.g. discretely spaced pile rows, Al-Defae and Knappett, 2014) may be more effective, but also
9 that for slopes of modest height (e.g. small embankments) tree roots may be a highly effective method of
10 improving seismic performance.

11 12 CONCLUSIONS

13 A series of centrifuge tests has been performed at different scales (1:10 and 1:30) and corresponding centrifugal
14 acceleration fields (10-g and 30-g, respectively) to investigate the performance of slopes of different heights
15 containing root analogues under a sequence of earthquake motions. The following principal conclusions can be
16 drawn from the study:

- 17 a) Amplification factors for all cases were observed to be significantly larger than the minimum value of
18 1.7 suggested by EC8. These observations would suggest that topographic amplification factors should
19 be substantially increased, particularly in taller slopes.
- 20 b) Filtering out the low frequency (high period) component of the motion, such as was necessitated by the
21 low scaling factor during centrifuge modelling has a significant effect on dynamic amplification of
22 motion within the slope when the frequency band is wide, but for narrow band motions with few low
23 frequency components, such effect is very limited. Such motions would be highly suitable for use in
24 centrifuge testing where different scaling factors are applied.
- 25 c) The dynamic response of the ground at the crest of the slope was found to be highly dependent on slope
26 height and not represented by site and topographic amplification factors which are independent of slope
27 height, as in current design codes. The dynamic response at the crest was also found to be largely
28 insensitive to previous shaking and the presence of vegetation.
- 29 d) The influence of vegetation on permanent displacement appears to be strongly dependent on the height
30 of the slope. In this study, smaller height vegetated slopes performed much better than taller slopes.
31 This indicates that there may be a limiting height of slope beyond which other, more traditional forms
32 of reducing seismic permanent deformation may be more effective. The reason for this appears to be a
33 combination of reduced accelerations within the slipping mass and a more significant change in failure
34 mechanism (and hence greater increase in yield acceleration) within the smaller slopes. This suggests
35 that for slopes of modest height (e.g. long low height embankments along transport infrastructure), tree
36 roots may be a very effective seismic slope stabilisation method. For soil conditions and slope
37 geometries similar to those considered herein, it would appear that slopes < 5 m tall (rooting depth > 30%
38 of slope height) will have their seismic performance substantially improved by the presence of roots.

1 Slopes taller than this or with shallower rooting depths are likely only to see a modest improvement to
2 seismic performance, and may therefore require other methods of improving their performance (e.g.
3 piling).

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9 Council.

11 NOTATION

21	c'_r	cohesion due to reinforcement
22	C_z	coefficient of uniformity
23	C_z	coefficient of curvature
24	D_{10}	particle diameter at which 10% is smaller
25	D_{30}	particle diameter at which 30% is smaller
26	D_{50}	particle diameter at which 50% is smaller
27	D_{60}	particle diameter at which 60% is smaller
28	e	void ratio
29	e_{max}	maximum void ratio
30	e_{min}	minimum void ratio
31	f_0	fundamental natural frequency
32	G_0	small strain shear modulus
33	G_s	specific gravity
34	g	acceleration due to gravity(=9.81 m/s ²)
35	H	soil layer (slope) height
36	I_D	relative density
37	k	coefficient for the shape of soli layer
38	K_0	coefficient of earth press at rest
39	M_s	surface wave magnitude
40	p'_0	initial mean effective confining stress
41	S	Soil factor describing the site effect
42	S_T	topographic amplification factor

S_{pk}	peak acceleration amplification factor
R	particle roundness
V_s	average shear wave velocity
z	depth
γ	unit weight
γ_{\max}	maximum unit weight
γ_{\min}	minimum unit weight
ρ	density
σ'_v	normal effective stress
ϕ'	effective angle of friction

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Table1. Summary of centrifuge models tested

Test identification number	Test scale	Slope height (m)	Root type	root cluster quantity	Motion frequency content (Hz)
TL 04	1:10	2.4	Fallow	0	4-30
TL 05	1:30	7.2	Fallow	0	1.33-10
TL 06	1:30	7.2	1:30 scale root cluster	36	1.33-10
TL 07	1:10	2.4	1:10 scale root cluster	4	4-30
TL 08	1:30	7.2	Fallow	0	4-10
TL 09	1:30	7.2	1:30 scale root cluster	36	4-10

Table2. State-independent physical properties of HST95 silica sand (After Lauder, 2010)

Property	Value
Specific gravity, G_s	2.63
D_{10} :mm	0.09
D_{30} :mm	0.12
D_{50} :mm	0.16
D_{60} :mm	0.17
C_u	1.9
C_z	1.06
Maximum void ratio, e_{max}	0.769
Maximum void ratio, e_{min}	0.467

Table 3. Root diameter class for medium and structural roots (not including tap root)

Diameter at 1:10 model scale (mm)	Number of roots	Diameter at 1:30 model scale (mm)	Number of roots	Diameter range at prototype scale (mm)	Root class at prototype scale (after Watson et al. 1995)
-	-	-	-	<5	fine
0.8	109	-	-	5-10	small
1.6	81	0.8	81	10-20	medium
3	43	1	43	20-40	large
5	13	1.6	13	>40	coarse

Table4. Sequence of input motions

Motion ID	Input motion	Peak input acceleration: a_g (g)		
		4-30 Hz	1.33-10 Hz	4-10 Hz
EQ1	Aegion,1995	0.12	0.21	0.15
EQ2	Northridge,1994	0.28	0.64	0.29
EQ3	Northridge,1994	0.28	0.64	0.29
EQ4	Northridge,1994	0.28	0.64	0.29
EQ5	L'Aquila,2005	0.23	0.27	0.29
EQ6	L'Aquila,2005	0.23	0.27	0.29
EQ7	L'Aquila,2005	0.23	0.27	0.29
EQ8	Aegion,1994	0.12	0.21	0.15

Fig.1: Schematic of centrifuge model geometry, instrumentation and position of root analogues: (a) 1:10 scale model; (b) 1:30 scale model (Dimensions at prototype scale in meters).

Fig.2: ABS plastic root models produced from 3-D printer showing the size difference between 1:10 scale and 1:30 scale models. Horizontal lines indicate potential shear plane depths at prototype scale.

Fig.3: 2D distribution of roots intersecting four planes at different depths below the ground surface (as shown in Fig. 2) for 3-D root models at prototype scale: (a) 1:10 scale; (b) 1:30 scale (downslope positive).

Fig.4: Schematic of large direct shear apparatus (DSA) – 1:10 scale model root cluster shown.

Fig.5: Comparison of DSA test results for 1:10 and 1:30 scale root clusters (depths at prototype scale): (a) variation of confining stress with depth; (b) additional shear strength provided by roots.

Fig.6: Normalised acceleration response spectra (ARS) of input motions as recorded in the field.

Fig.7: Normalised ARS of filtered input motions for centrifuge testing: (a) Aegion; (b) Northridge; (c) L'Aquila.

Fig.8: Comparison of peak acceleration amplification between 'full' and reduced frequency content input motions at 1:30 scale: (a) in EQ1 (Aegion); (b) in EQ2 (Northridge); (c) in EQ5 (L'Aquila).

Fig.9: Acceleration amplification factor in the frequency domain: (a) 1:30 scale model at full frequency content; (b) 1:30 scale model at reduced frequency content.

Fig.10: Comparison of ARS-derived amplification factor between 1:30 scale models at full and reduced frequency content: (a) in EQ1; (b) in EQ2; (c) in EQ5.

Fig.11: Effect of slope height on peak acceleration amplification: (a) in EQ1; (b) in EQ2; (c) in EQ5.

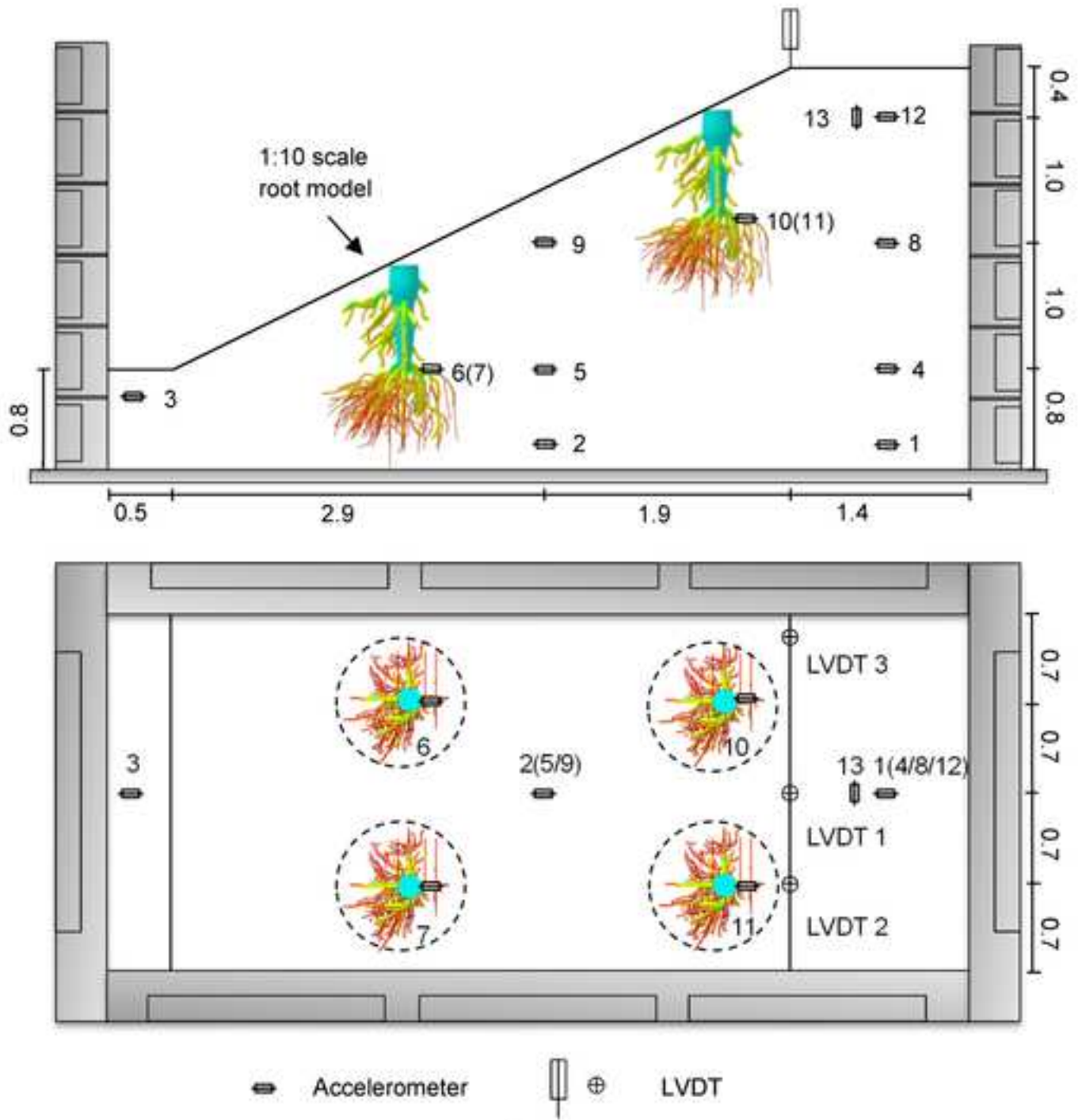
Fig.12: Increased peak ground motion amplification in aftershocks, 1:30 scale fallow model (TL 05) shown.

Fig.13: Comparison of permanent settlement at the crest in fallow slopes: (a) effect of input motion frequency content; (b) effect of slope height.

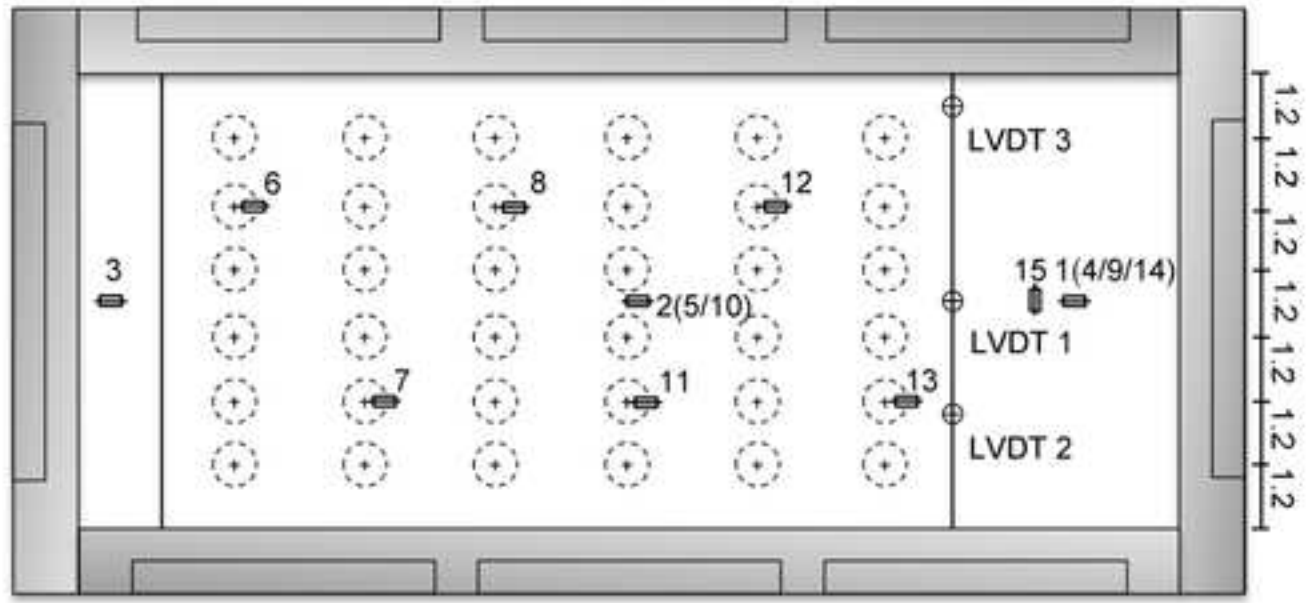
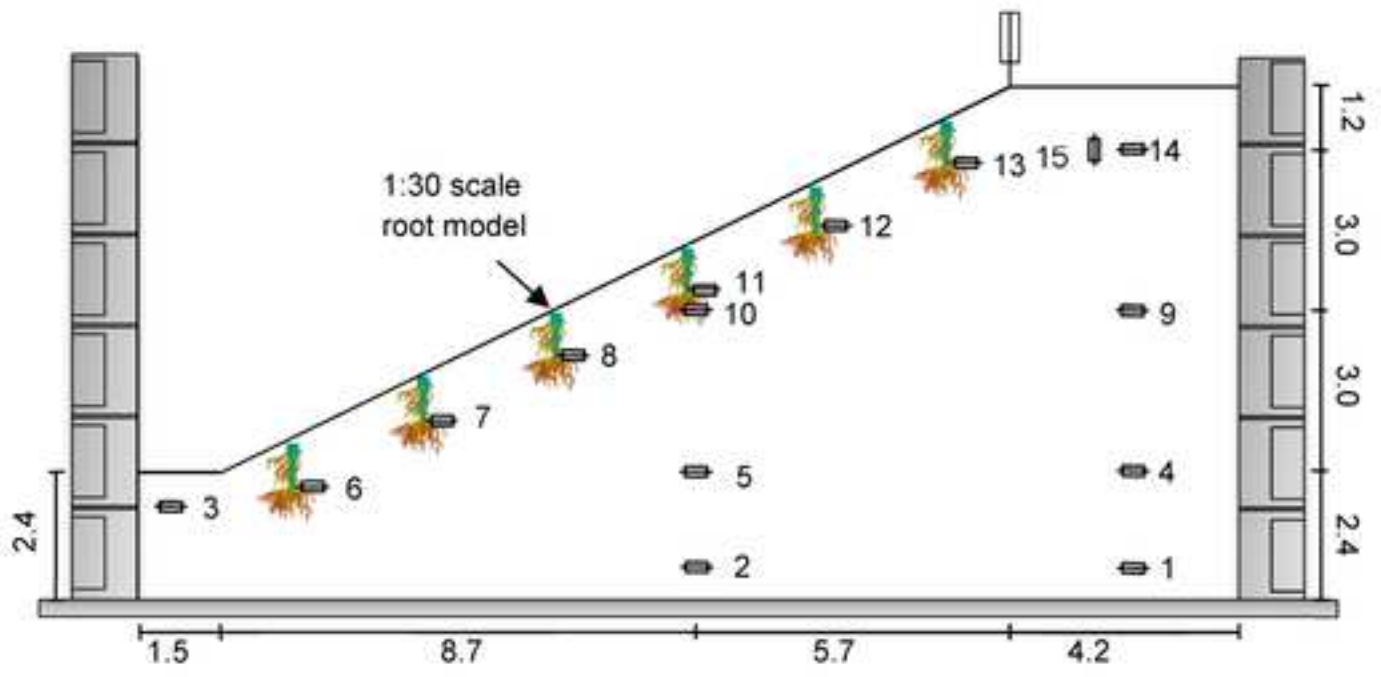
Fig.14: Comparison of shear modulus degradation and damping between fallow and root reinforced slopes: (a) 1:10 scale models; (b) 1:30 scale models at reduced frequency content; (c) 1:30 scale models at full frequency content.

Fig.15: Reduction in peak acceleration due to the presence of roots: (a) 1:10 scale model; (b) 1:30 scale model at reduced frequency content; (c) 1:30 scale model at full frequency content.

Fig.16: Comparison of permanent crest settlements between fallow and root-reinforced slopes: (a) 1:10 scale models; (b) 1:30 scale models at reduced frequency content; (c) 1:30 scale models at full frequency content.

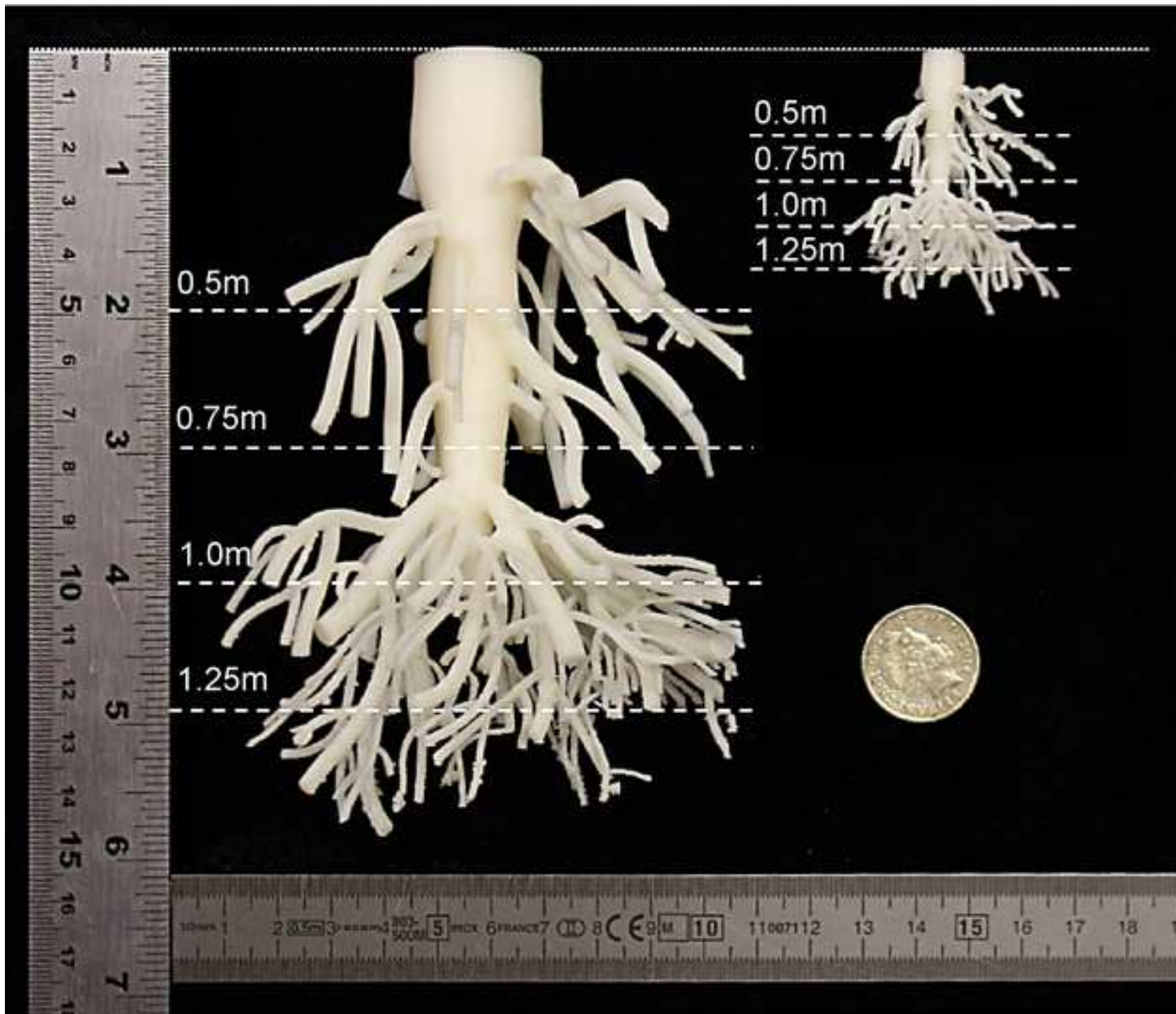


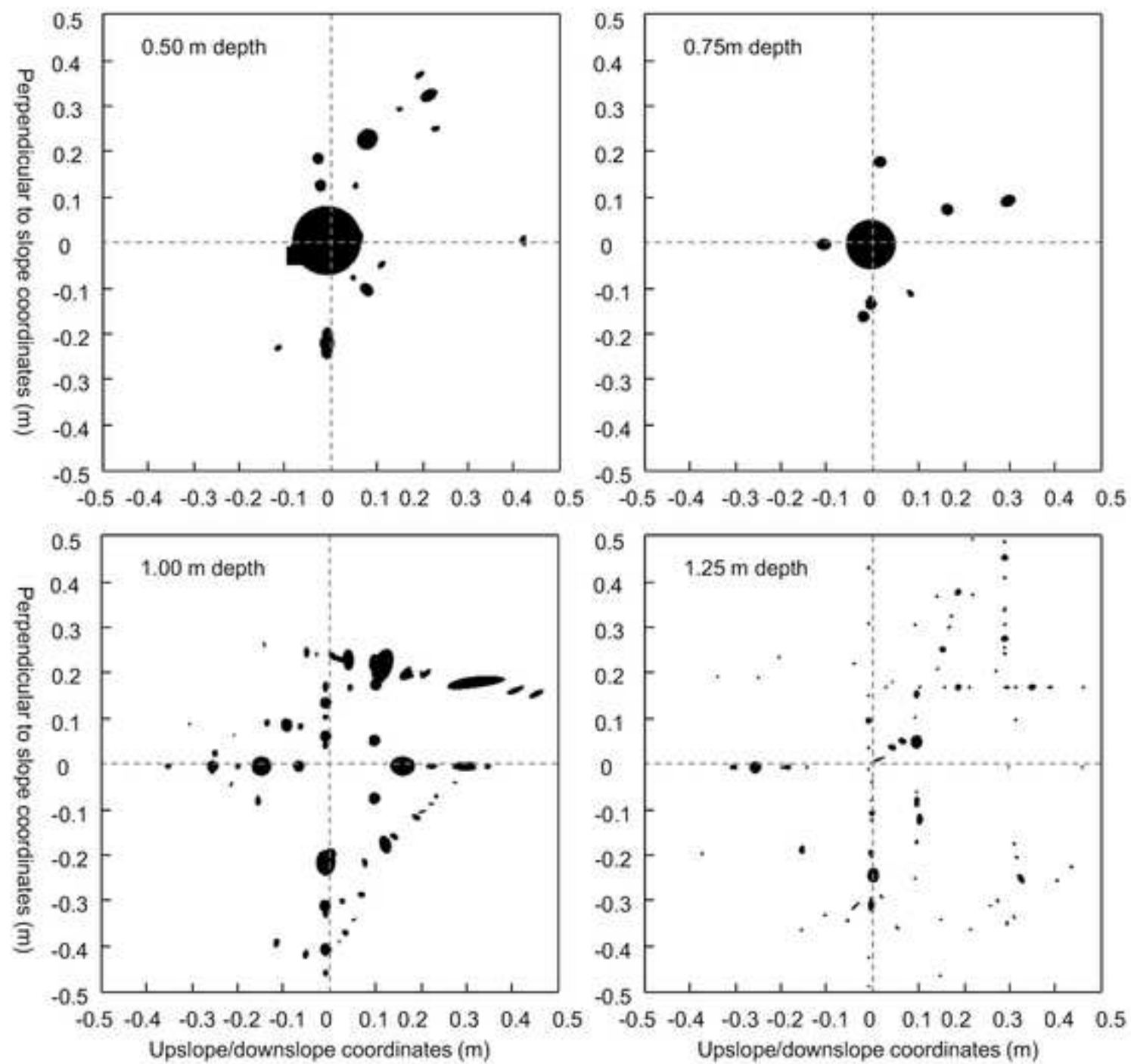
(a)

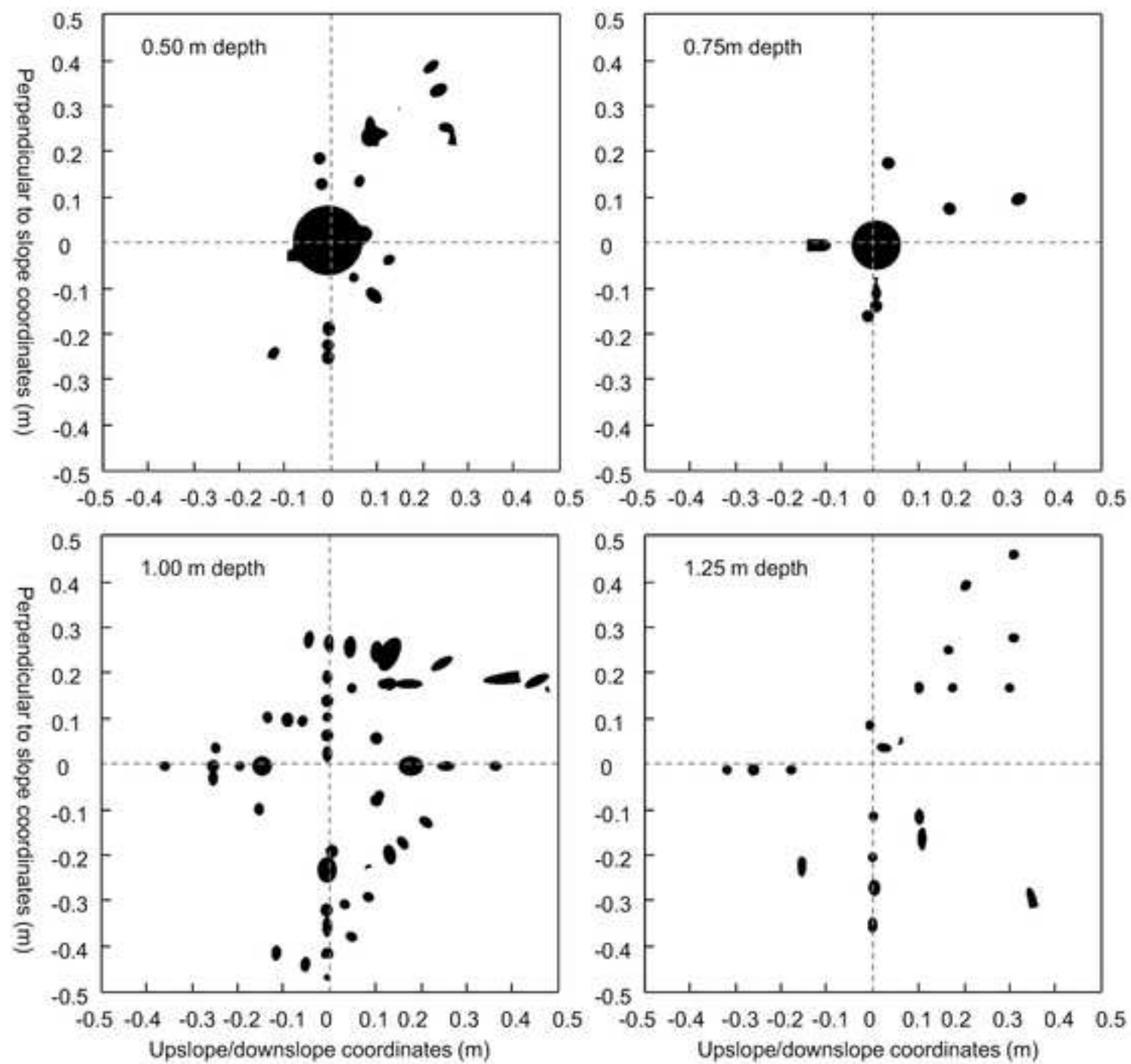


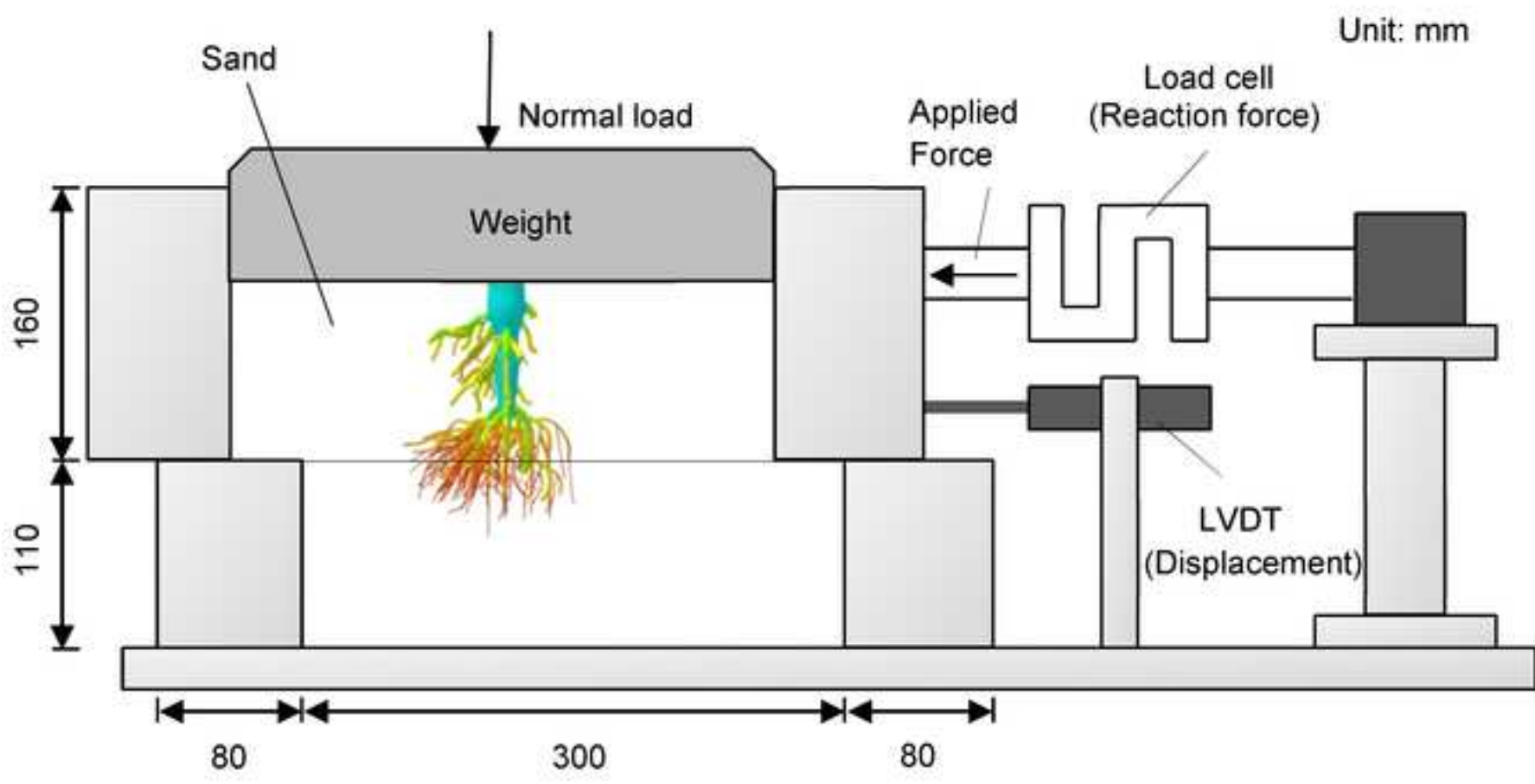
Accelerometer LVDT

(b)

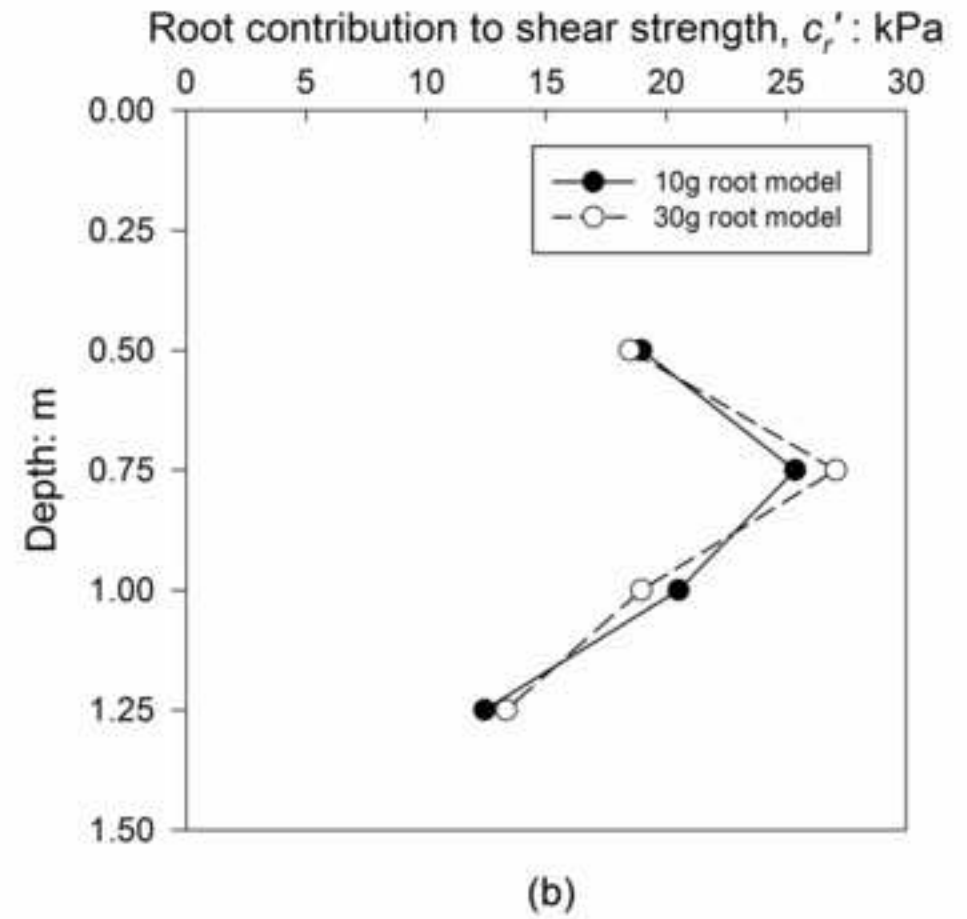
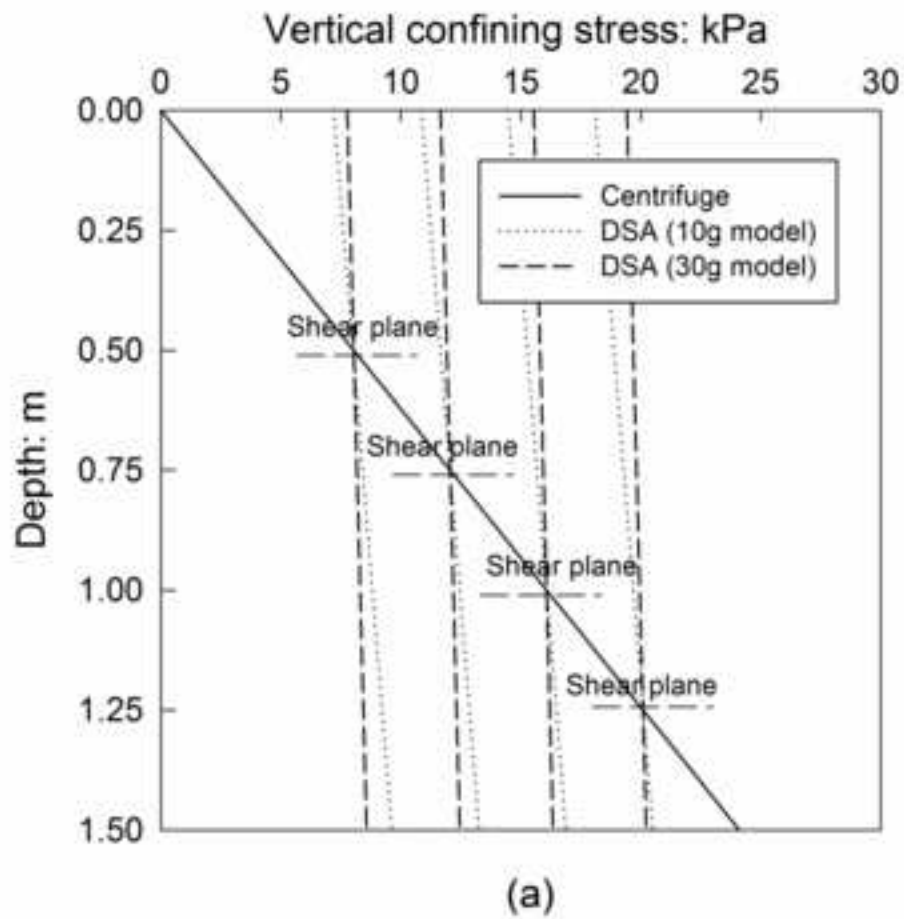


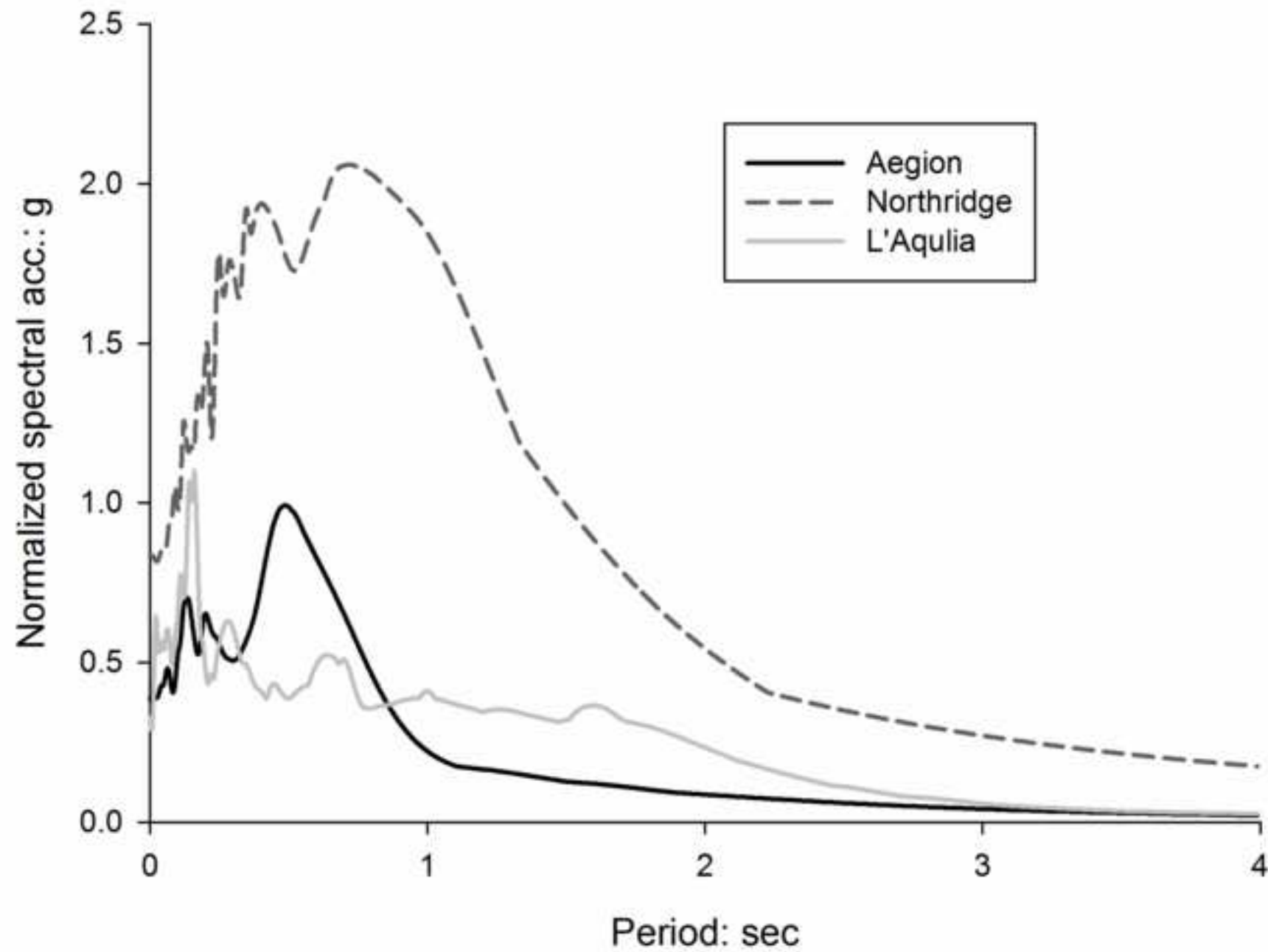


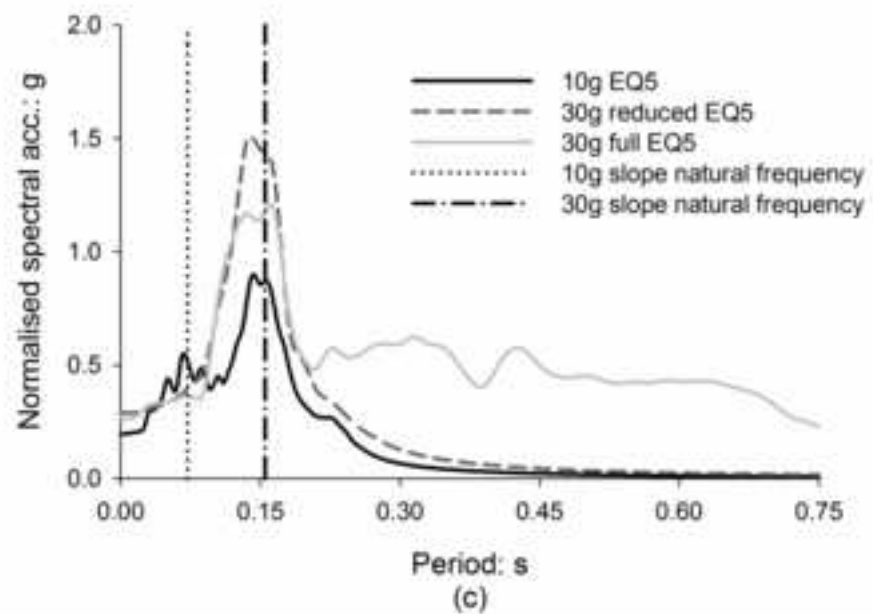
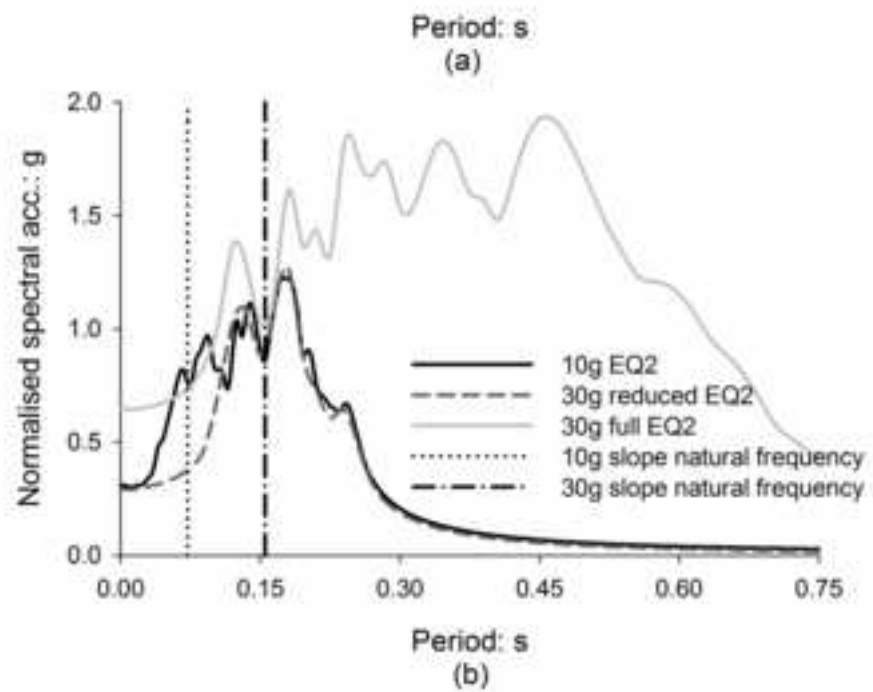
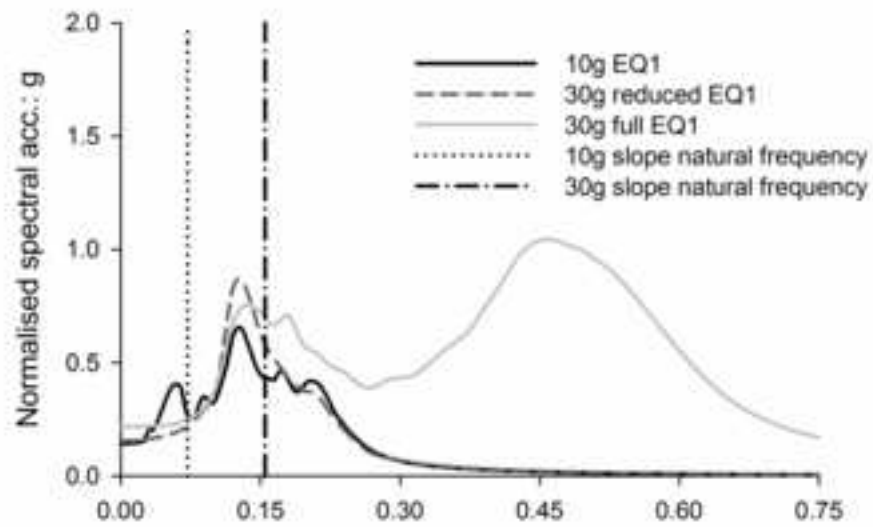


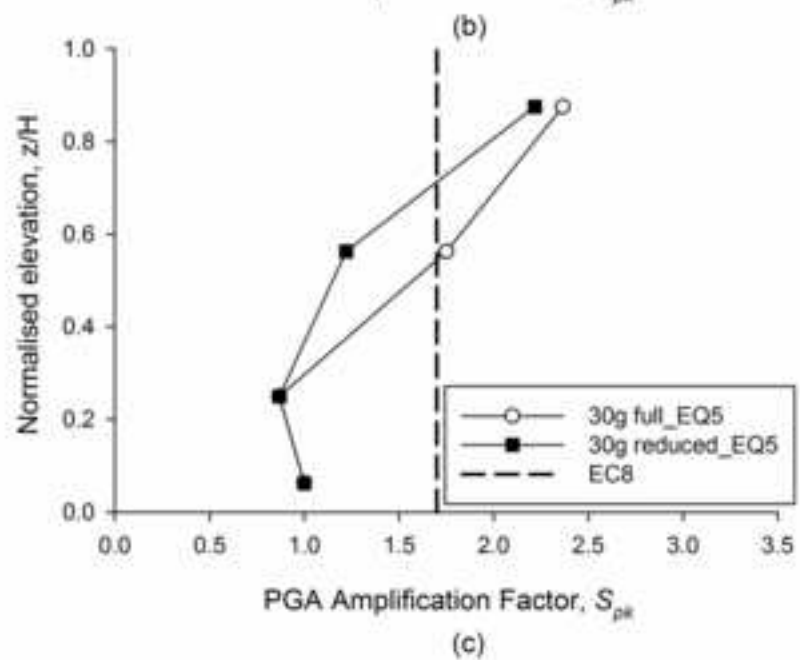
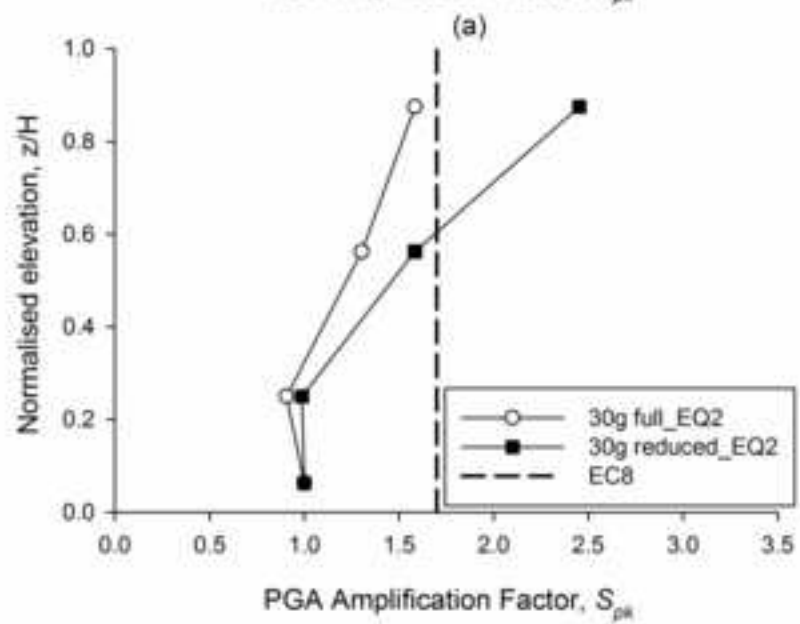
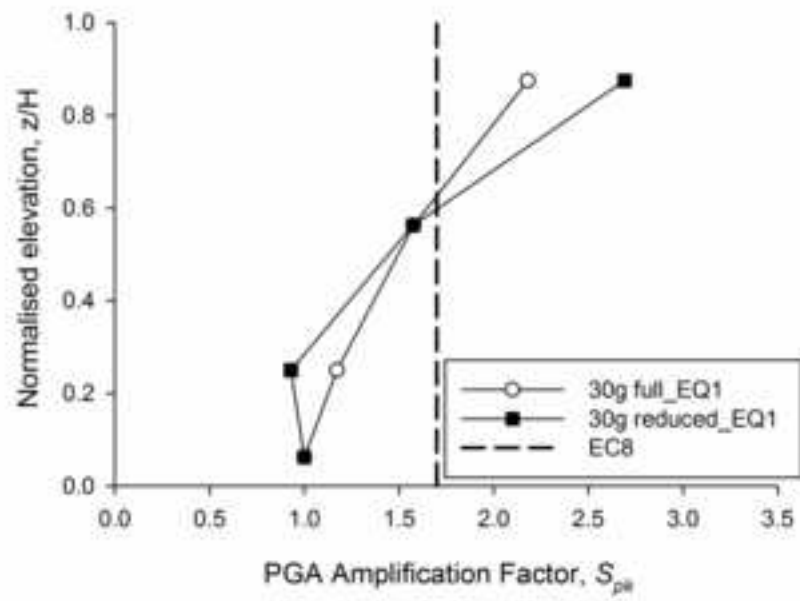


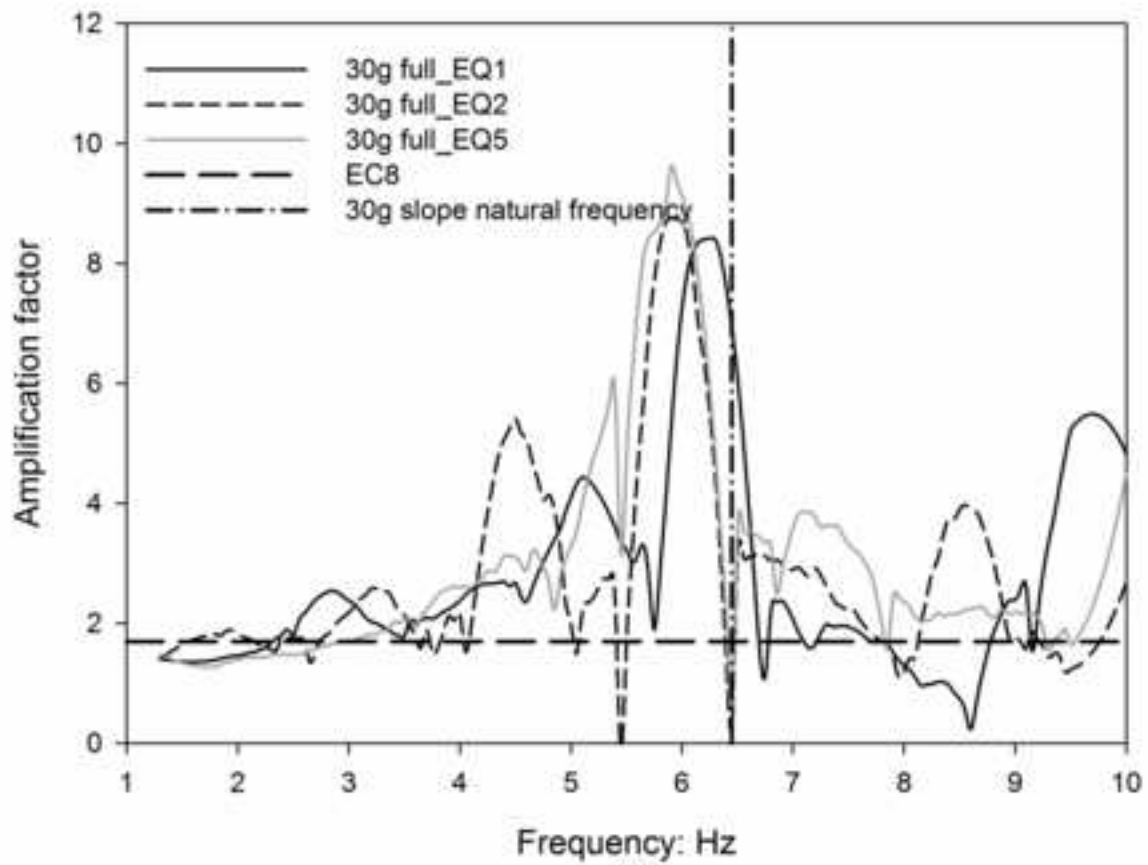
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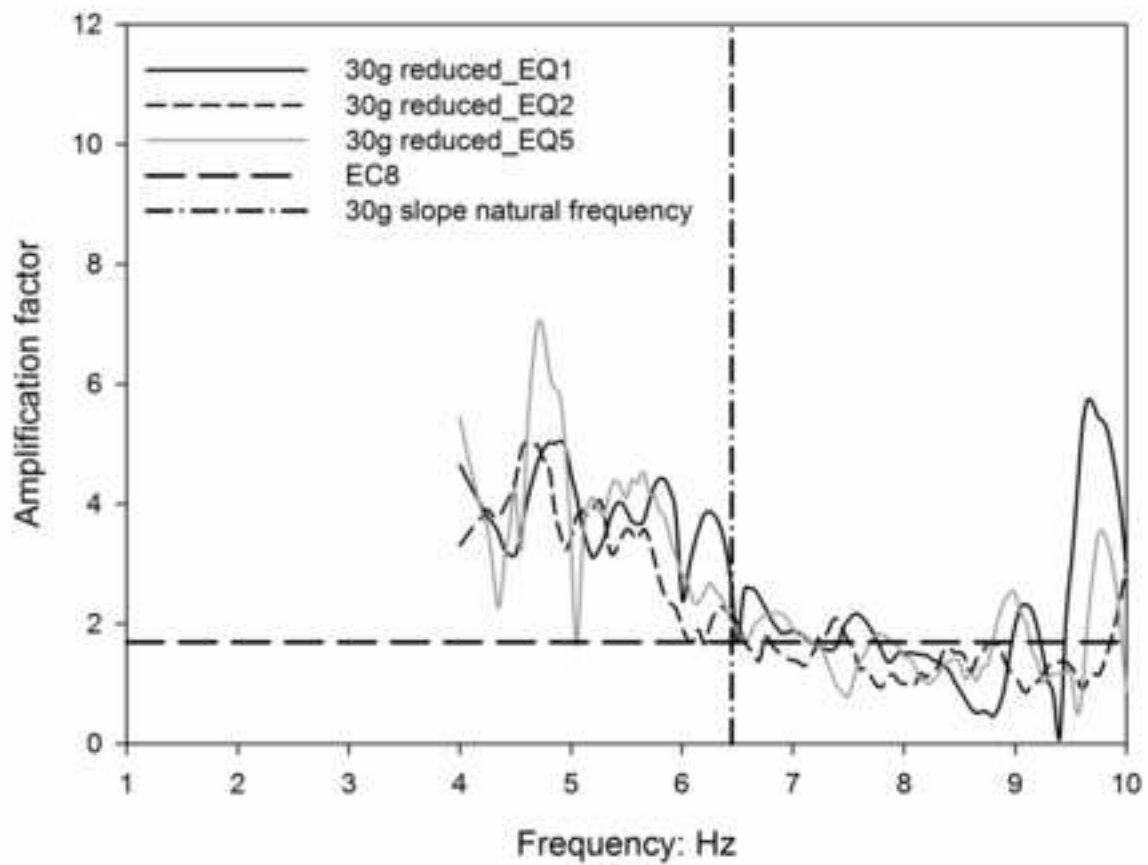




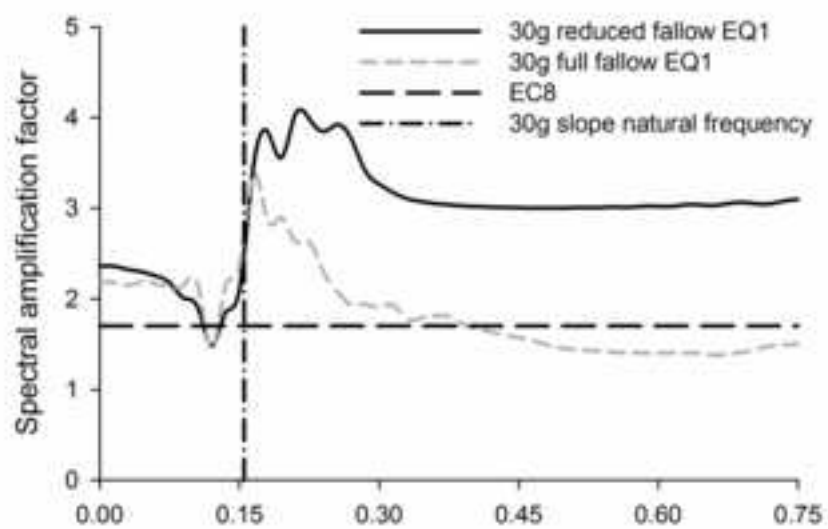




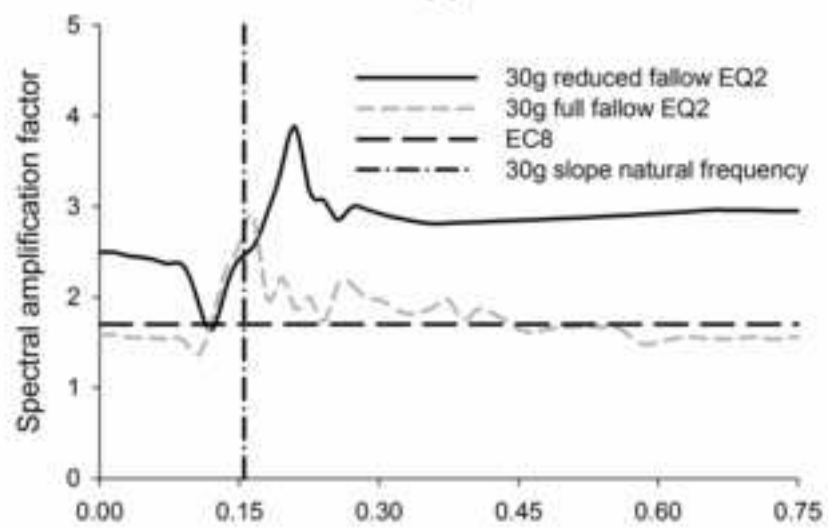
(a)



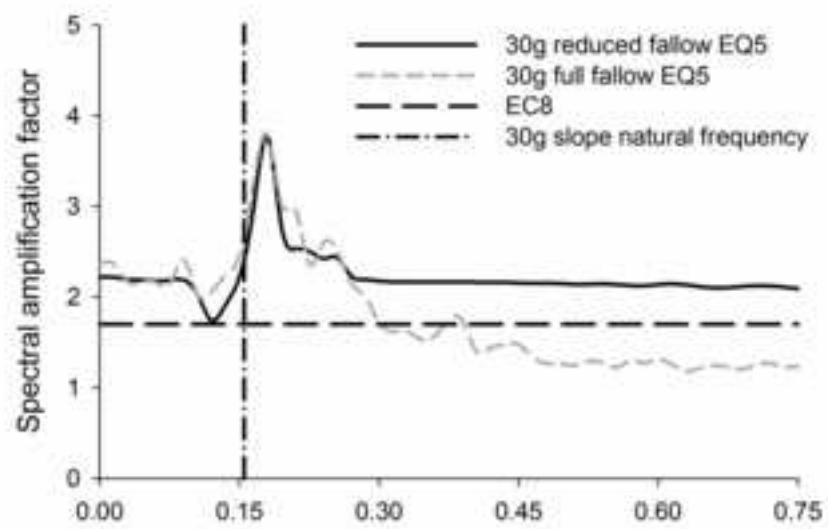
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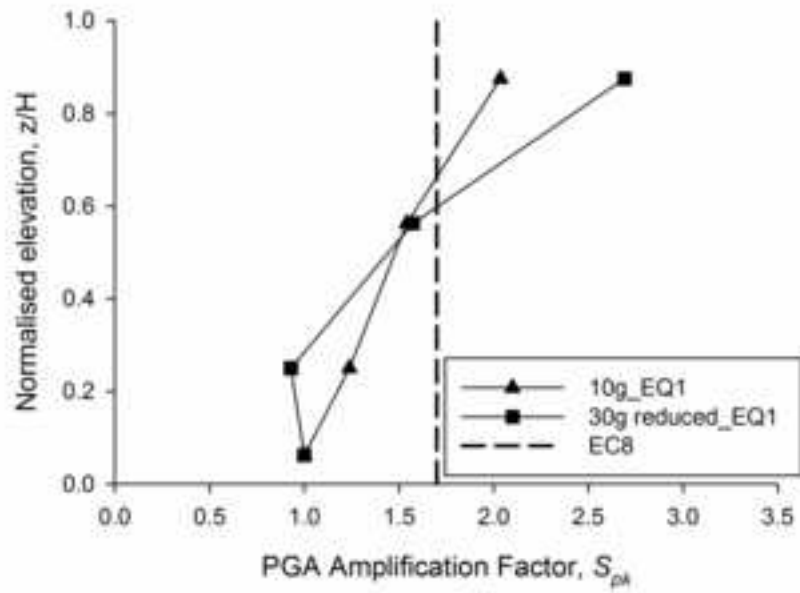
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(a)



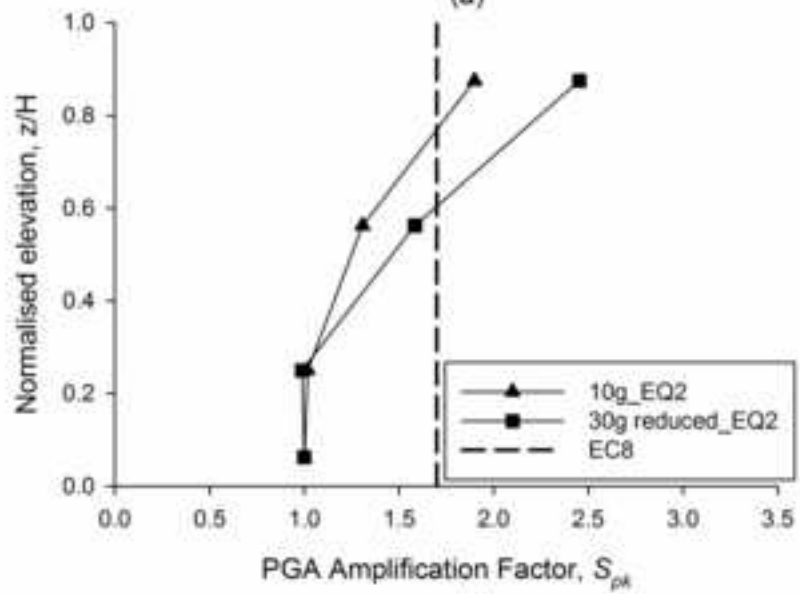
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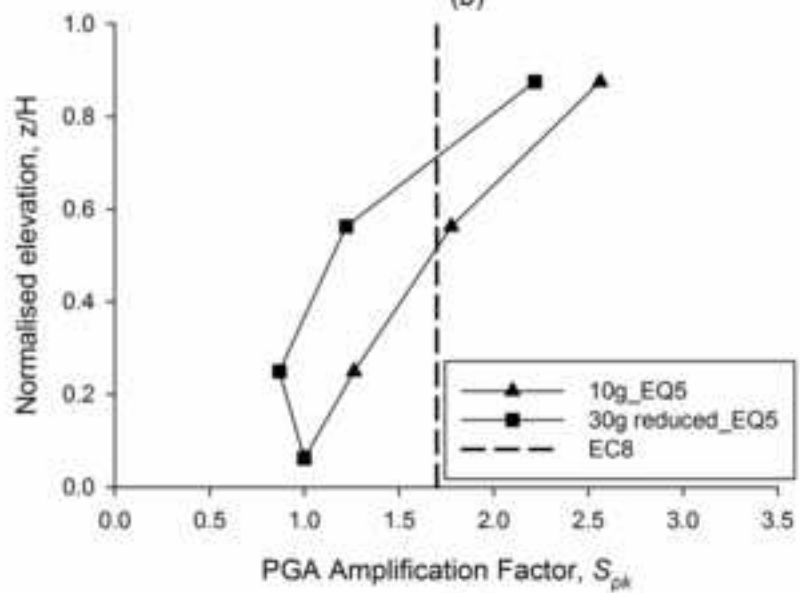
Period: s
(c)



(a)



(b)



(c)

