

Contents

Preface *xiii*

Part I Materials 1

1	Extreme Mechanics of Hydrogels Toward <i>In Situ</i> Hydrogel Bioelectronics	3
	<i>Tsz H. Wong, Xuanhe Zhao, and Shaoting Lin</i>	
1.1	Introduction	3
1.2	Extreme Properties of Hydrogels by Polymer Network Design	5
1.2.1	Elastic Modulus	6
1.2.2	Fracture Toughness	8
1.2.3	Fatigue Threshold	11
1.2.4	Mass Transport	12
1.3	Stretchable Hydrogel Conductors	14
1.3.1	Multiscale Orthogonal Design	14
1.3.2	Implementations of the Orthogonal Design	15
1.4	Electrochemical Hydrogel Biosensors	18
1.4.1	Selective Transport Design of Hydrogels	19
1.4.2	Electrochemical Design of Hydrogel-2D Material Interfaces	20
1.5	Flexible Hydrogel Biobattery	20
1.5.1	Mechanical Energy Harvester	21
1.5.2	Chemical Energy Harvesters	22
1.5.3	Thermal Energy Harvesters	23
1.6	Concluding Remarks	23
	Acknowledgments	24
	References	25
2	Multiscale Mechanics of Metal Nanowire-Based Stretchable Electronics	37
	<i>Shuang Wu and Yong Zhu</i>	
2.1	Introduction	37
2.2	Metal NW-Based Flexible and Stretchable Electronics	38

2.3	Mechanics of Individual NWs	39
2.3.1	Overview of Mechanics of Metal NWs	40
2.3.2	Mechanics of Single-Crystalline Metal NWs	40
2.3.3	Mechanics of Bi-Twinned Metal NWs	42
2.3.4	Mechanics of Penta-Twinned Metal NWs	43
2.4	Interfacial Mechanics of the NW–Polymer Interface	45
2.4.1	Classic Theory of Shear-Lag Analysis	45
2.4.2	Shear-Lag Analysis Considering Bonding Mechanisms	46
2.4.3	Fracture of NWs Due to Shear Stress Transfer	49
2.4.4	Elastoplastic Analysis of Metal NWs	51
2.5	Mechanical Design of Stretchable Structures	54
2.5.1	Buckle-Delamination Enabled Stretchable Silver Nanowire Conductors	54
2.5.2	A Highly Sensitive, Stretchable, and Robust Strain Sensor Based on Crack Advancing and Opening	55
2.6	Concluding Remarks	58
	Acknowledgments	59
	References	60

3 Liquid Metal-Based Electronics 69

Carmel Majidi

3.1	Introduction	69
3.1.1	Ga-Based Liquid Metals	69
3.1.2	Relevant Literature	71
3.2	LM Architectures	71
3.2.1	Microfluidic LM Channels	71
3.2.1.1	Printing-Based Deposition Methods	72
3.2.1.2	Direct LM Casting	73
3.2.2	LM-Coated Thin-Film Metal Traces	73
3.2.3	LM–Polymer Composites	74
3.2.4	Printable LM-Based Inks	76
3.3	Mechanics and Modeling	76
3.3.1	Microfluidic LM Strain Gauge	76
3.3.2	Microfluidic LM Pressure Sensor	77
3.3.3	LM–Polymer Composites	79
3.3.3.1	Electrical Permittivity and Thermal Conductivity	79
3.3.3.2	Electromechanical Coupling	79
3.3.3.3	Effective Young’s Modulus	80
3.4	Open Challenges and Future Directions	81
	References	82

4 Mechanics of Two-Dimensional Materials 87

Olugbenga Ogunbiyi and Yingchao Yang

4.1	Introduction	87
4.2	Nanoindentation Method	90

4.3	AFM-Enabled Nanoindentation	93
4.3.1	Setup of AFM-Enabled Nanoindentation	93
4.3.2	Mechanical Testing of 2D Materials	95
4.3.2.1	Mechanical Testing of Graphene	95
4.3.2.2	Mechanical Testing of Graphene Oxide (GO)	101
4.3.2.3	Mechanical Testing of MoS ₂	103
4.3.2.4	Mechanical Testing of WSe ₂	103
4.3.2.5	Mechanical Testing of <i>h</i> -BN	105
4.3.2.6	Mechanical Testing of Black Phosphor (BP)	107
4.4	<i>In Situ</i> Indentation in SEM	108
4.4.1	Raman Spectroscopy	110
4.5	Micro-/Nano-mechanical Devices	111
4.5.1	Category of Micromechanical Devices	111
4.5.1.1	Thermal Actuated Micromechanical Devices	111
4.5.1.2	Micromechanical Devices with Push–Pull Mechanism	112
4.5.2	Development of the “Dry-Transfer” Technique	113
4.5.3	Mechanical Testing of 2D Materials	115
4.5.3.1	Mechanical Testing of Graphene	115
4.5.3.2	Mechanical Testing of Rebar Graphene	117
4.5.3.3	Mechanical Testing of MoSe ₂	117
4.5.3.4	Mechanical Testing of <i>h</i> -BN	118
4.6	Piezoelectric Tube-Driven Testing in TEM	120
4.7	Bulge Testing	121
4.7.1	Depressurize Inside and Form a Concave Deflection in Film	121
4.7.2	Depressurize Outside and Form a Convex Deflection in Film	122
4.8	Electrostatic Force Triggered Drum Structure	124
4.9	Phonon Dispersion Measurement	125
4.10	Summary	126
4.10.1	Mechanical Testing Techniques	126
4.10.2	Mechanical Properties of 2D Materials	127
	Disclosure Statement	128
	References	128

5 Mechanics of Flexible and Stretchable Organic Electronics 139

Abdullah Al Shafe and Brendan T. O'Connor

5.1	Introduction	139
5.2	Mechanical Characterization Methods	140
5.2.1	Tensile Tests	141
5.2.2	Fracture Toughness	143
5.2.3	Thermomechanical Behavior	143
5.3	Material Design	145
5.3.1	Molecular Weight	145
5.3.2	Backbone and Side-Chain Design	146
5.3.3	Regioregularity and Crystallinity	147

5.3.4	Block Copolymers with Flexible and Stretchable Linkers	148
5.3.5	Crosslinking and Hydrogen Bonding	148
5.3.6	Additives and Blends	150
5.3.7	Organic Photovoltaic Considerations	152
5.4	Device Design	153
5.4.1	Neutral Axis and Ultrathin Devices	153
5.4.2	Film Thickness	153
5.4.3	Electrodes and Interlayers	155
5.4.4	Interfaces	155
5.4.5	Stretchable Device Architecture	156
5.5	Applications	156
5.6	Conclusion	159
	Acknowledgments	159
	References	160

Part II Design and Manufacturing 171

6	Structural Design of Flexible and Stretchable Electronics	173
	<i>Zhaoqian Xie, Zichen Zhao, and Raudel Avila</i>	
6.1	Introduction	173
6.2	Design of Planar Stretchable and Flexible Structures	174
6.2.1	Wave/Wrinkle Structure Design	174
6.2.2	Island–Bridge Structure Design	177
6.2.2.1	Straight Interconnecting Island–Bridge Structure	178
6.2.2.2	Serpentine Interconnecting Island–Bridge Structure	180
6.2.2.3	Fractal-Inspired Interconnecting Island–Bridge Structure	186
6.3	Design of Three-Dimensional Flexible Electronic Structures	189
6.3.1	Helical Design	189
6.3.2	Origami-Inspired Design	190
6.3.3	Kirigami-Inspired Design	192
6.4	Design of Protective Structures for Flexible Electronic Devices	193
6.4.1	Strain Limited Structure Design	193
6.4.2	Strain Isolation Structure Design	195
	References	202
7	Laser-Based Fabrication Process Development for Flexible and Stretchable Electronics	207
	<i>Jung Jae Park, Minwoo Kim, and Seung Hwan Ko</i>	
7.1	Introduction	207
7.2	Representative Laser-Based Fabrication Process	208
7.3	Applications Based on Laser Fabrication	211
7.4	Perspectives and Conclusion	225
	Author Contributions	226
	References	226

8	Electrospinning Manufacturing of Stretchable Electronics	235
	<i>Yinhui Li, Kan Li, Yunlei Zhou, and YongAn Huang</i>	
8.1	Background	235
8.2	High-Precision Manufacturing	236
8.2.1	Inkjet Printing	236
8.2.2	EHD Printing	239
8.3	Electrospinning Stretchable Structure	243
8.3.1	Stretchable Nanofiber Mats	243
8.3.2	Stretchable Yarns and Fabrics	244
8.4	Application in Stretchable Electronics	247
8.4.1	Strain and Pressure Sensor	247
8.4.2	Organic Field-Effect Transistors	248
8.4.3	Optoelectronic Devices	252
8.5	Conclusions	254
	References	254
9	Mechanics-Guided 3D Assembly of Flexible Electronics	265
	<i>Guoquan Luo, Jianzhong Zhao, Xu Cheng, and Yihui Zhang</i>	
9.1	Introduction	265
9.2	Design Strategies of Mechanics-Guided Assembly	266
9.2.1	2D Precursor Designs	267
9.2.1.1	Origami/Kirigami Design Strategy	267
9.2.1.2	Multilayer and Multilevel Design Strategy	267
9.2.1.3	Design Strategy Based on Spatial Stiffness Control	269
9.2.2	Elastomer Substrate Designs	270
9.2.2.1	Engineered Planar Substrate Design Strategy	270
9.2.2.2	Curvilinear Substrate Design Strategy	272
9.2.3	Strategy of Loading Conditions	272
9.2.3.1	Mechanical Loading Strategy	272
9.2.3.2	Electric/Magnetic-Field-Assisted Loading Strategy	274
9.3	Mechanics Modeling and Analyses of the 3D Assembly	275
9.3.1	Buckling Analysis of 2D Precursors	275
9.3.1.1	Straight Ribbons	275
9.3.1.2	Helical Structures	277
9.3.1.3	Frame Structures	278
9.3.1.4	2D Curved Ribbons	278
9.3.2	Interfacial Adhesion in the Mechanics-Guided Assembly	279
9.3.2.1	Design Diagrams of Delamination States	279
9.3.2.2	Controlled Interface Delamination	281
9.3.3	Loading-Path Controlled Assembly	282
9.3.3.1	Reconfigurable Cross-Shaped Structures	282
9.3.3.2	Reconfigurable Structures Harnessing Interface Mechanics	282
9.4	Applications of 3D Flexible Electronics	284
9.4.1	Flexible Sensors	284

- 9.4.2 Tunable Electromagnetic Devices 284
- 9.4.3 Biomedical Devices 286
- 9.4.4 Flexible Robotics 286
- 9.5 Concluding Remarks 287
- References 288

10 **Harnessing Wrinkling and Buckling Instabilities for Stretchable Devices and Healthcare** 293

Yao Zhao, Fangjie Qi, Haoze Sun, Yanbin Li, Haitao Qing, and Jie Yin

- 10.1 Introduction 293
- 10.2 Structural Designs and Mechanics 294
 - 10.2.1 Structural Designs for Buckling-Enabled Stretchability 294
 - 10.2.2 Mechanics of Wrinkling and Buckling 296
 - 10.2.2.1 Compression-Induced Wrinkling 297
 - 10.2.2.2 Compression-Induced Constrained Buckle-Delamination 298
 - 10.2.2.3 Compression-Induced Spontaneous Buckle-Delamination 298
 - 10.2.2.4 Tension-Induced Buckling in Serpentine Structures 299
 - 10.2.2.5 Tension-Induced Buckling in Kirigami Structures 300
- 10.3 Applications in Stretchable Devices 300
 - 10.3.1 Stretchable Sensors 300
 - 10.3.2 Stretchable Batteries 302
 - 10.3.3 Other Stretchable Electronics 304
- 10.4 Applications in Healthcare 306
 - 10.4.1 Biosensors 306
 - 10.4.2 Biological Interfaces 308
- 10.5 Conclusion and Outlook 311
- Acknowledgments 311
- References 311

Part III Applications 319

11 **Spherical Indentation Behavior of Soft Electronics** 321

Changxian Wang, Zequn Cui, and Xiaodong Chen

- 11.1 Spherical Indentation of the Semi-infinite Solid 321
 - 11.1.1 General Solution for Elastic Solid with Displacement Function 321
 - 11.1.2 Indentation Behavior of Revolution Indenter 325
 - 11.1.3 Indentation Behavior of Spherical Indenter 327
- 11.2 Applications in a Force-Softness Bimodal Sensor Array for Human Body Feature Identification 328
 - 11.2.1 Design of the Spherical Indenter-Based Force-Softness Sensor 329
 - 11.2.1.1 The First Stage 331
 - 11.2.1.2 The Second Stage 332
 - 11.2.2 Integration of the Force-Softness Sensor Array: Tactile Glove 334
 - 11.2.3 Applications in Body Feature Identification 336

11.3	Applications in a Self-Locked Young's Modulus Sensor for Quantifying the Softness of Swollen Tissues in the Clinic	336
11.3.1	Design of the Fingertip Modulus Sensor	337
11.3.2	Applications in Softness Measurement of Swollen Tissues in the Clinic	340
11.4	Conclusions	343
	References	343
12	Mechanics of Wet Adhesion	345
	<i>Jiawei Yang and Ruobing Bai</i>	
12.1	Introduction	345
12.2	Characterization of Adhesion	346
12.3	General Principles for Strong Wet Adhesion	347
12.3.1	Chemistry of Bonds	349
12.3.1.1	Static Covalent Bonds	349
12.3.1.2	Dynamic Covalent Bonds	349
12.3.1.3	Ionic Bonds	349
12.3.1.4	Hydrogen Bonds	350
12.3.1.5	Hydrophobic Interaction	350
12.3.1.6	π - π Stack	351
12.3.1.7	Dipole-Dipole Interaction	351
12.3.1.8	Host-Guest Interaction	351
12.3.1.9	Catechol Chemistry	351
12.3.2	Topology of Connection	351
12.3.3	Mechanics of Dissipation	352
12.4	Methods for Strong Wet Adhesion	354
12.5	Mechanics of Wet Interfaces	357
12.5.1	Adhesive Failure and Cohesive Failure	357
12.5.2	Fractocohesive Length- and Size-Dependency	358
12.5.3	Rate Dependency	359
12.5.4	Fatigue	360
12.5.5	Stretchable Adhesion	361
12.6	Summary and Outlook	362
	References	363
13	Electromechanics of Soft Resistive and Capacitive Tactile Sensors	373
	<i>Zhengjie Li, Sangjun Kim, Zheliang Wang, Zhengtao Zhu, and Nanshu Lu</i>	
13.1	Introduction	373
13.1.1	Overview of Tactile Sensors	373
13.1.2	Bottlenecks of Soft Resistive and Capacitive Tactile Sensors	376
13.2	Resistive Tactile Sensors	378
13.2.1	Introduction of Resistive Tactile Sensors	378
13.2.2	Resistive Tactile Sensors Based on Microstructured Contact	379

13.2.3	Resistive Tactile Sensors Based on Bulk Conductive Nanocomposites	385
13.2.4	Resistive Tactile Sensors Based on Porous Conductive Materials	392
13.2.5	Stretchable Resistive Tactile Sensors	397
13.3	Capacitive Tactile Sensors	399
13.3.1	Introduction of Capacitive Tactile Sensors	399
13.3.2	Capacitive Tactile Sensors with Engineered Dielectrics	401
13.3.3	Capacitive Tactile Sensors with Engineered Electrodes	408
13.3.4	Stretchable Capacitive Tactile Sensors	413
13.4	Resistive–Capacitive Hybrid Response Tactile Sensors	415
13.4.1	Flexible Hybrid Response Tactile Sensors	415
13.4.2	Stretchable Hybrid Response Tactile Sensors	417
13.5	Conclusion and Outlook	418
13.5.1	Summary of the Existing Achievements	418
13.5.2	Remaining Challenges and Future Prospects	419
	Acknowledgments	420
	References	420

14 Active Mechanical Haptics Constructed with Curved Origami 431

Zhuang Zhang and Hanqing Jiang

14.1	Introduction	431
14.2	Stiffness Tuning via Curved Origami	432
14.3	Theoretical Modeling and Analysis of Curved Origami	434
14.3.1	Geometric Modeling	434
14.3.2	Mechanics Modeling	436
14.3.3	Active Tuning	437
14.4	Closed-Loop Design and System Integration of Origami	438
14.5	In-hand Haptic Device	440
14.6	Stiffness Perception via Active Pressing	443
14.7	Body-Centered Stepping Device	444
14.8	Whole-Body Stiffness Perceptions	447
14.9	Discussion	448
	References	450

15 Mechanics of Transient Electronics 453

Ankan Dutta and Huanyu Cheng

15.1	Introduction	453
15.2	Hydrolysis of Semiconducting Materials	455
15.3	Model of Reactive Diffusion for Transient Materials	457
15.4	Dissolution of the Device with Bi-layered Structures	461
15.5	Conclusion	467
	Acknowledgments	468
	References	468