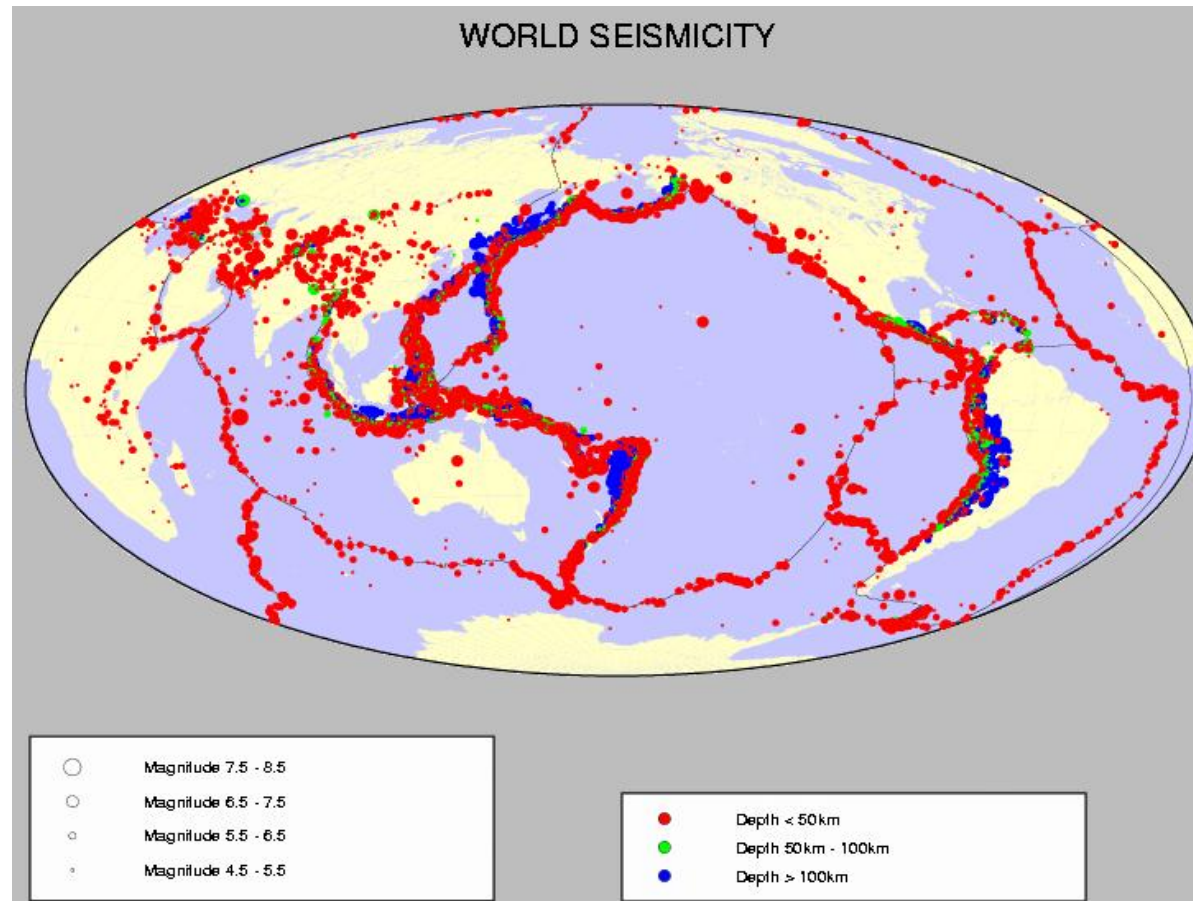


RIGID PLATE TECTONICS

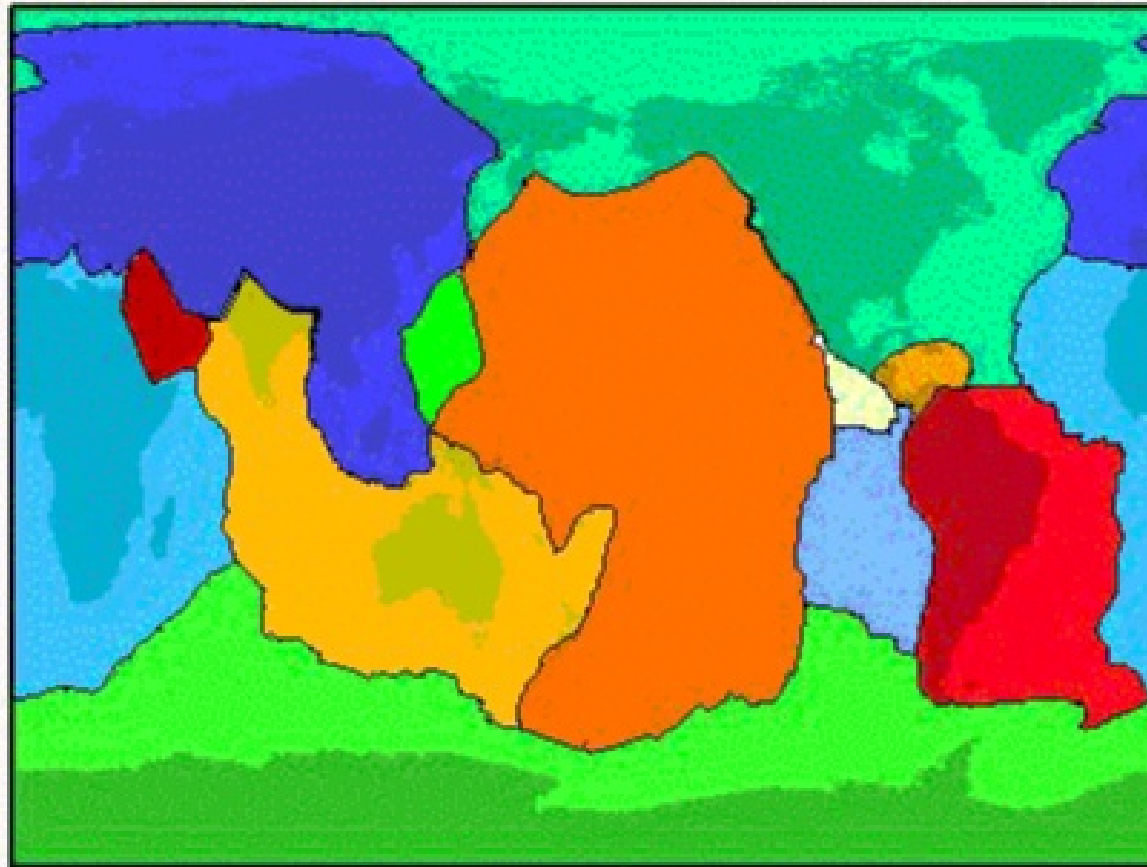
- Plate definition
- Plate motion : Euler pole
- Geological model : Nuvel-1A
- Geodetic model : ITRF
- Rigid plate rotations
- Plate deformation : strain and rotation tensors

World seismicity



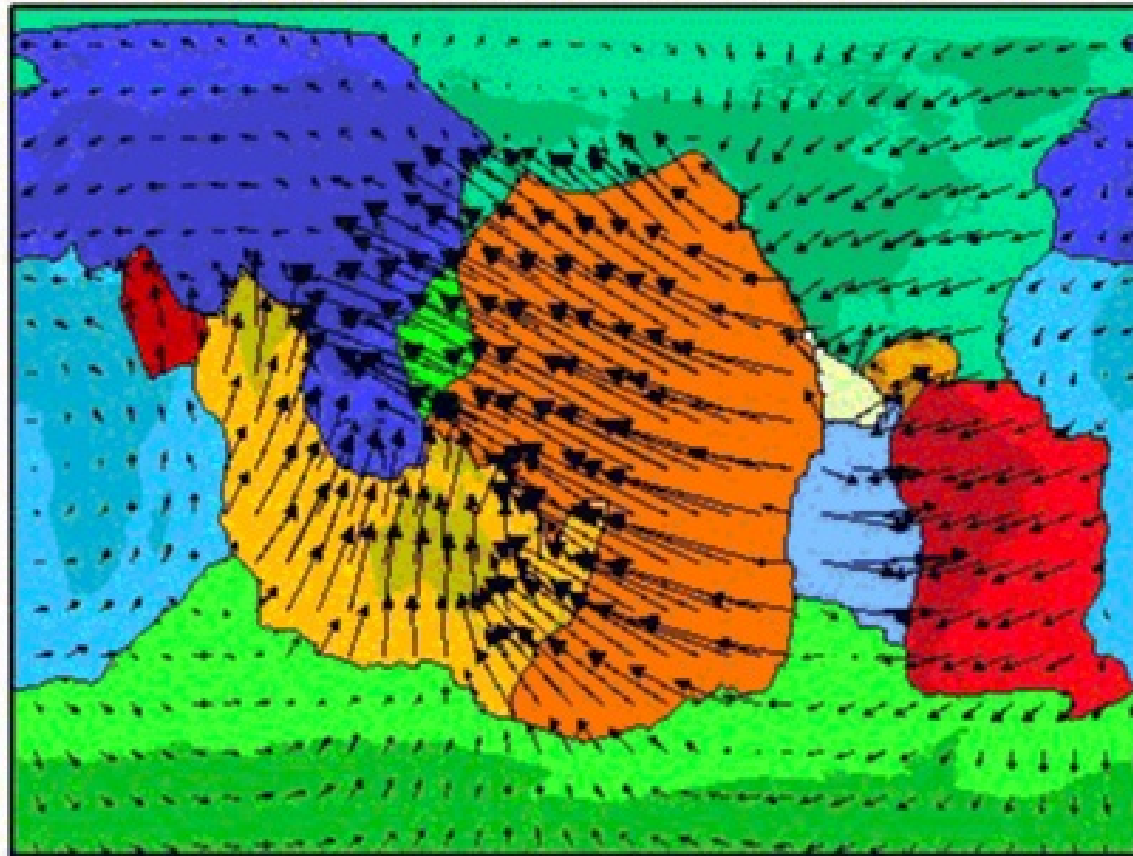
The Earth surface is cut by seismic « lines », separating quite areas, i.e. plates.

Plate geometry



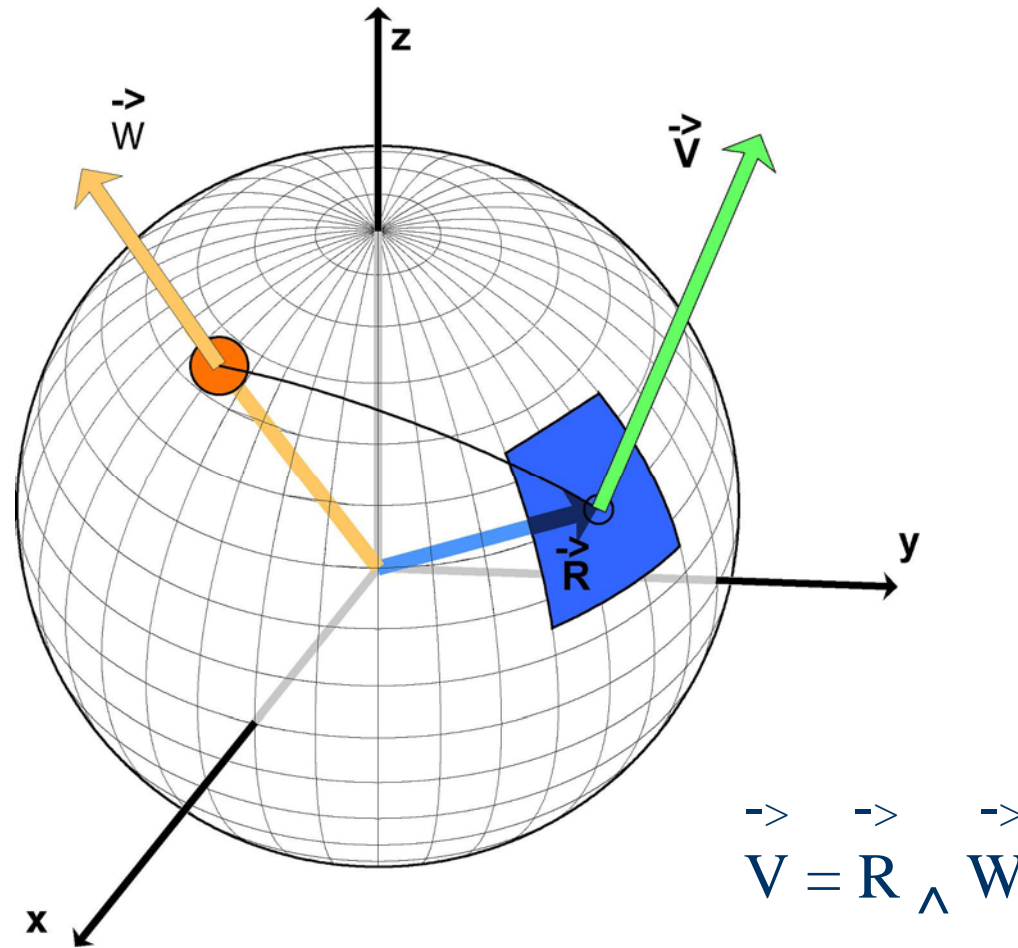
There are 12 main plates

Plate motion

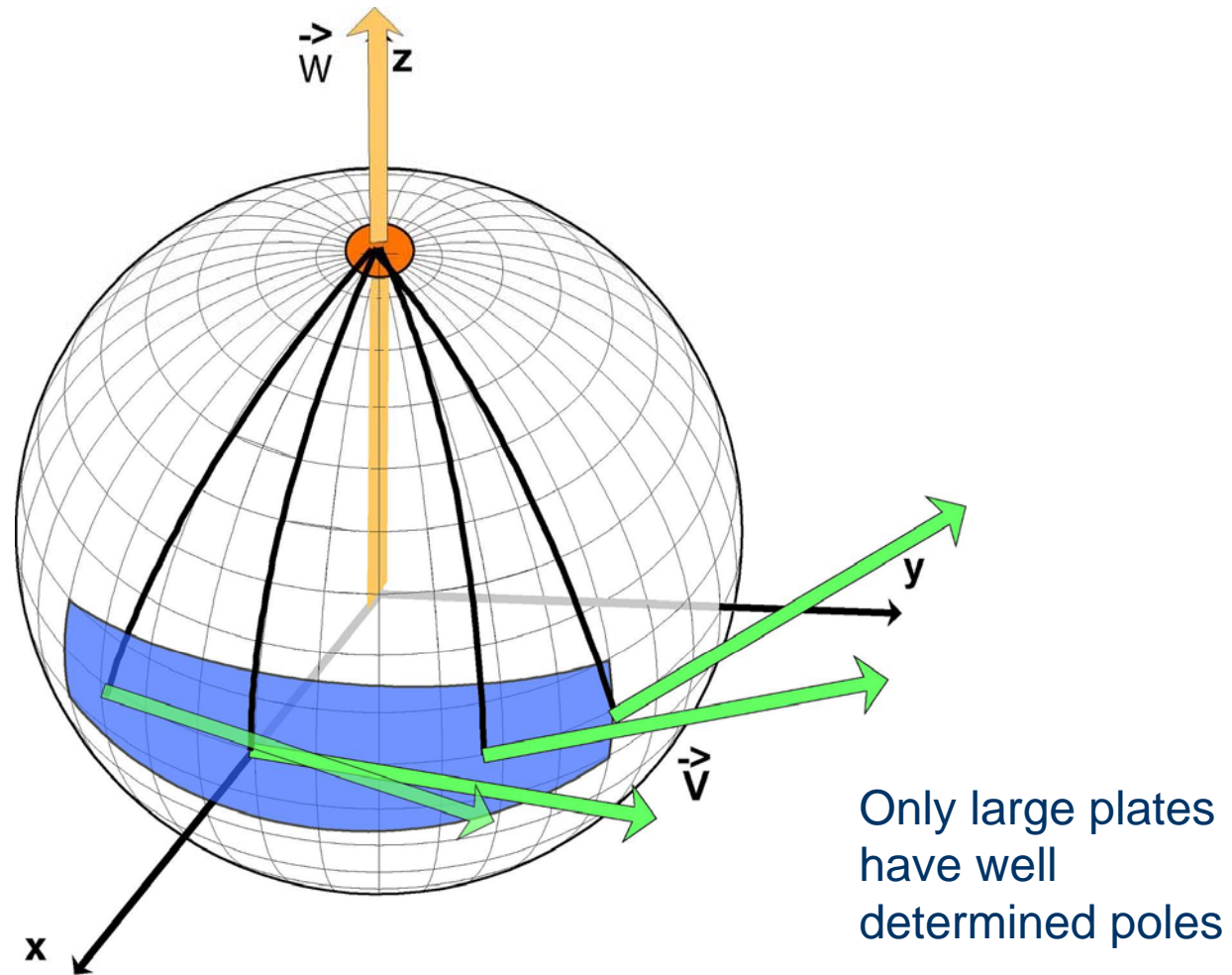


Plates move : it is plate tectonics

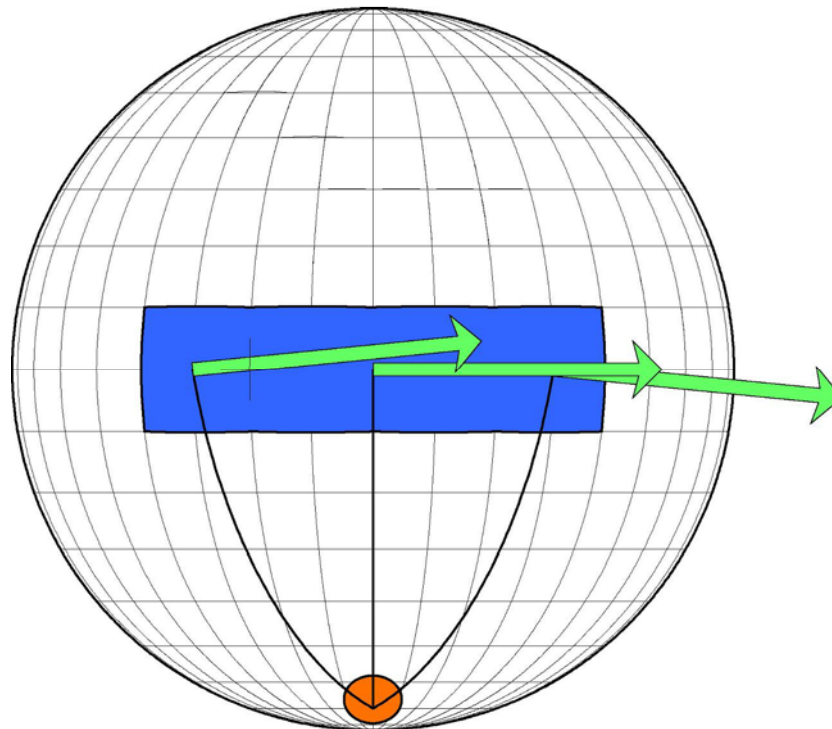
Rotation on a sphere



Finding a pole



Effect of velocity uncertainty



Slightly different velocities can give very different poles

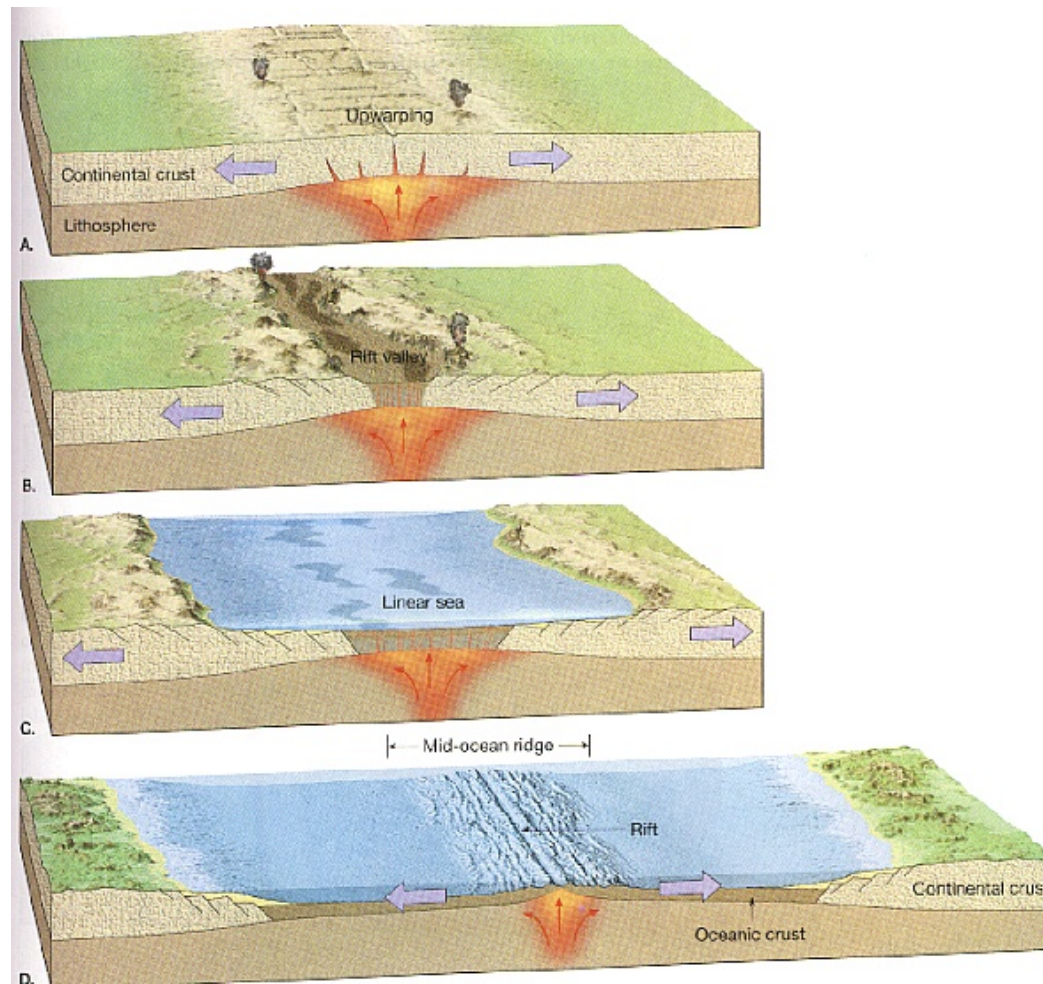
Or reverse :

Very different poles can give quite similar velocities

Pole positions don't matter.
only velocities do !!!!

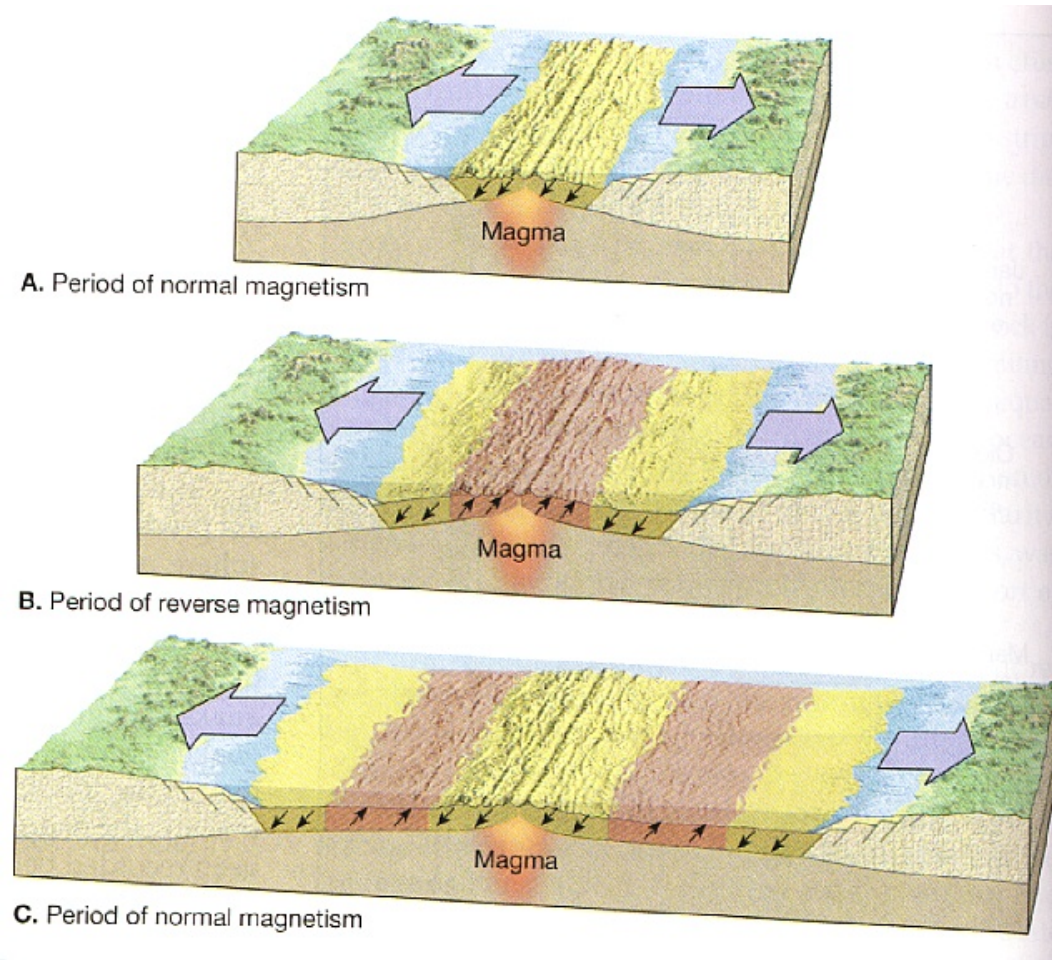
Geological model : how it works

Rates : continental drifting



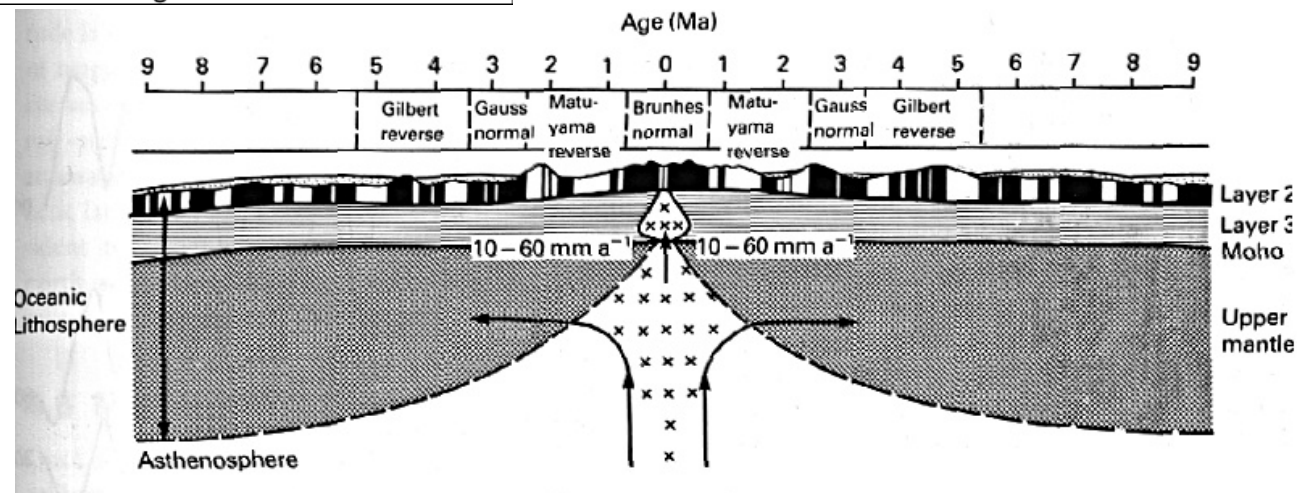
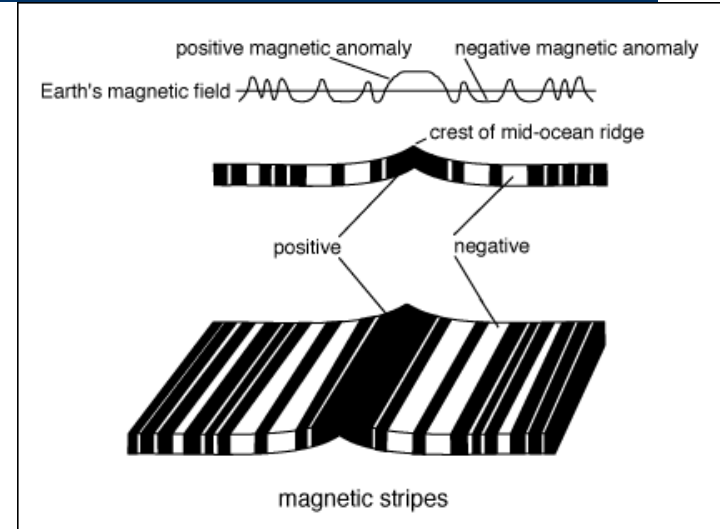
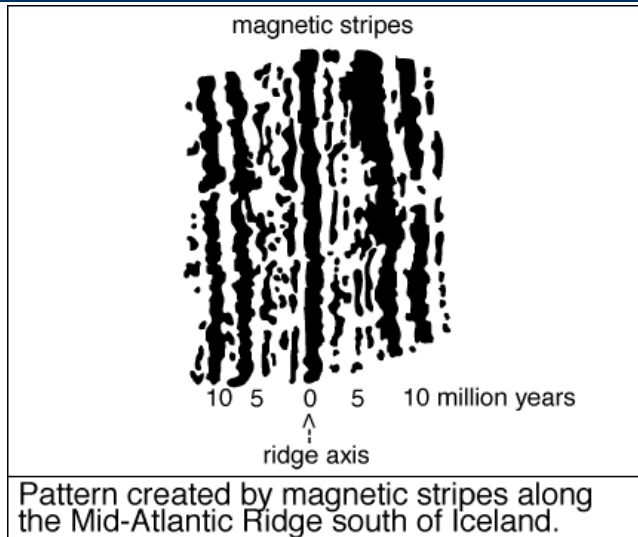
Geological model : how it works

Rates : generation of oceanic crust and sea floor magnetic anomalies



Geological model : how it works

Rates : Vine and Matthews hypothesis



Geological model : how it works

Rates : uncertainties from magnetic time scale

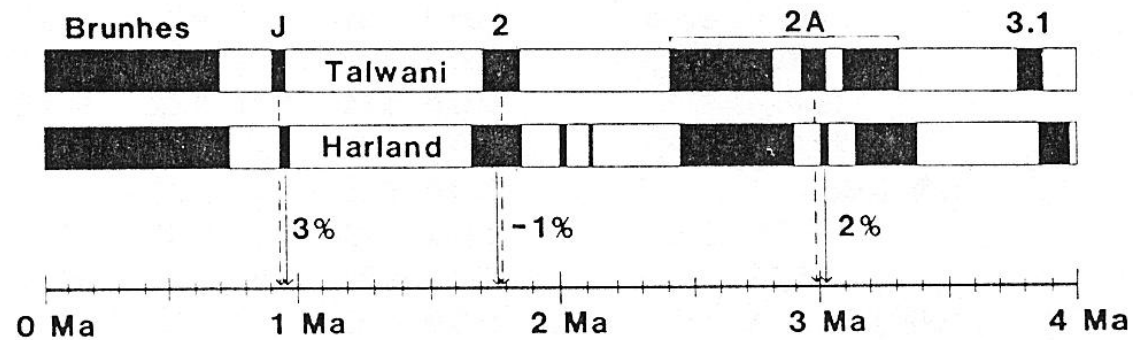
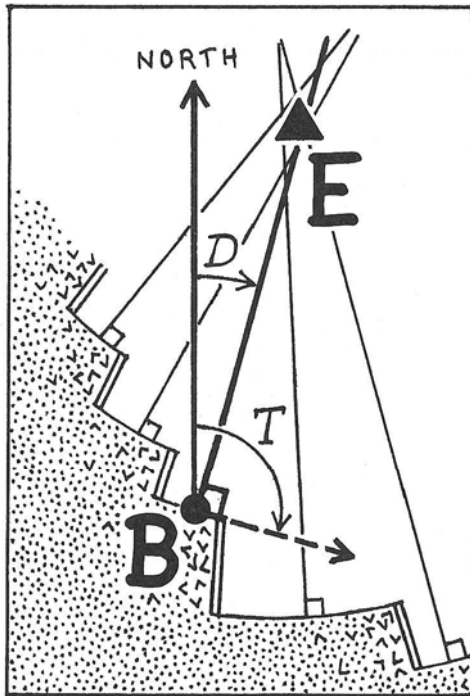


Figure 1. Comparison since 4.0 Ma of the geomagnetic reversal time-scale used here (Harland *et al.* 1982) with the time-scale used by Chase (1978) and Minster & Jordan (1978) (Talwani *et al.* 1971). We determined rates by seeking the best fit to the centre of anomaly 2A, which is 2 per cent older in the Harland *et al.* time-scale than in the Talwani *et al.* time-scale.

Geological model : how it works directions



$$D = T \pm 90^\circ$$

Figure 4-1. Locating an Euler pole **E** from the trends *T* of transforms. Lines nearly intersecting at **E** are great circles perpendicular to the transforms.

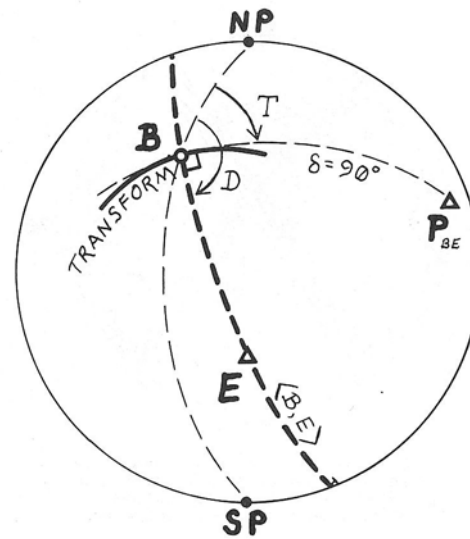


Figure 4-2. Euler pole **E** is on the great circle perpendicular to the trend of the transform. P_{BE} is the pole of the great circle $\langle B, E \rangle$.

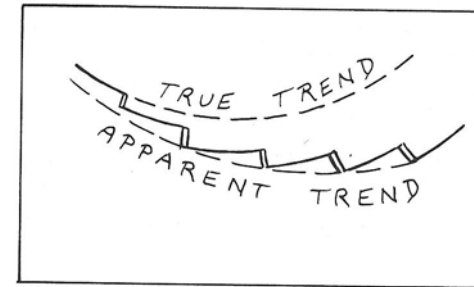
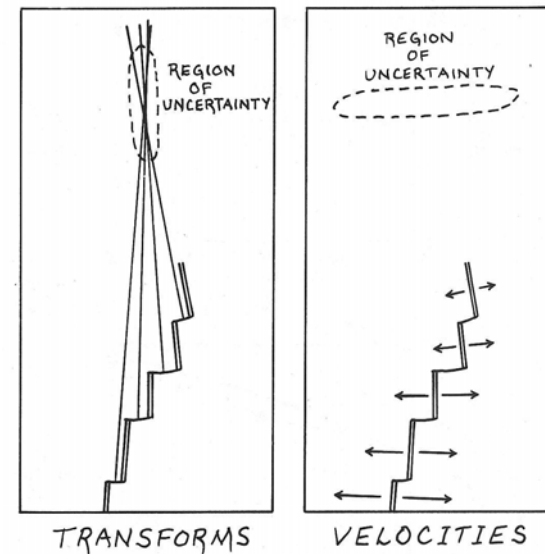


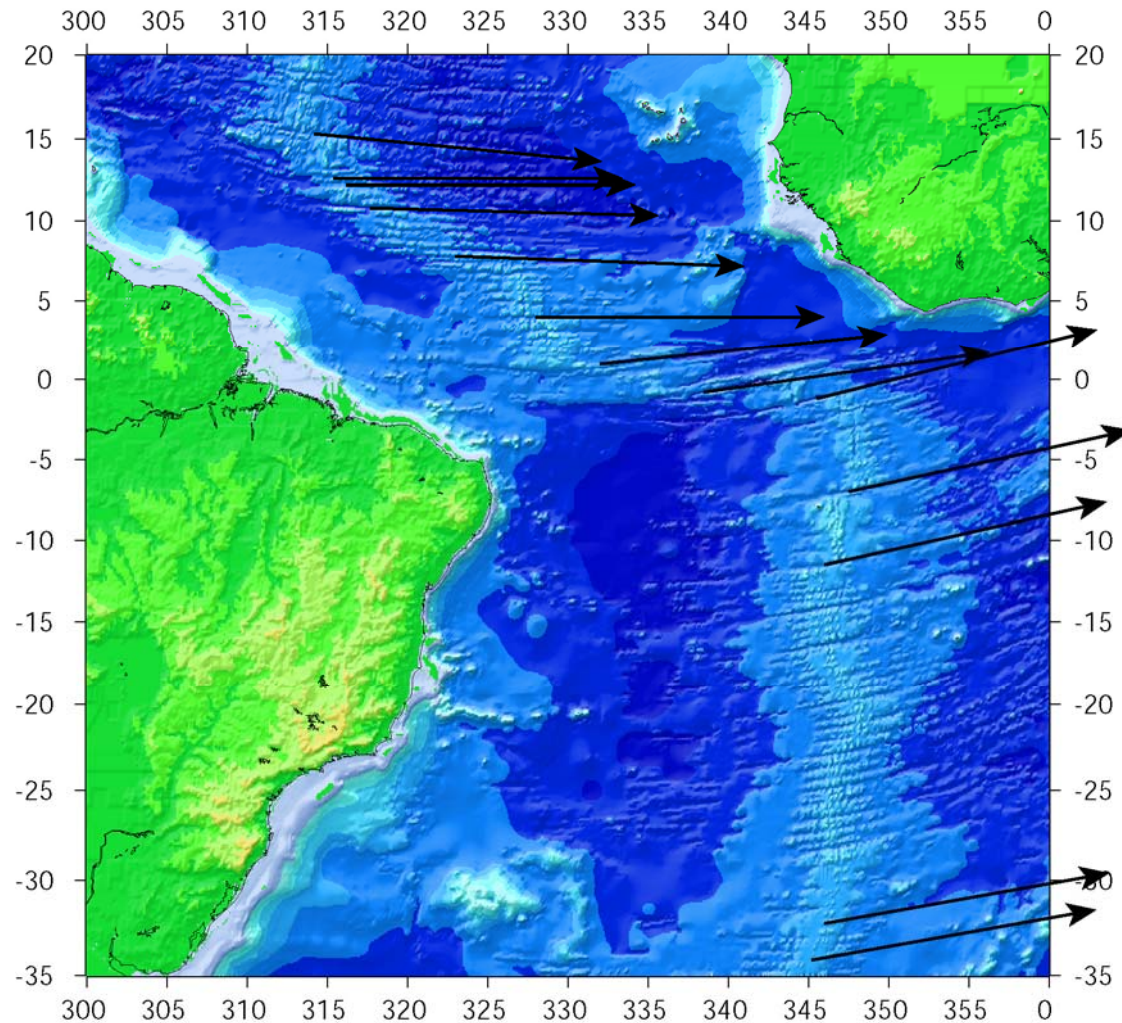
Figure 4-3. Apparent and true trends of transform system offset by short ridge segments.



Geological model : real data

Transform faults azimuths

Lon	lat	azimuth
15.3	-45.8	95.5
12.6	-44.6	90.0
12.2	-43.8	90.0
10.8	-42.3	91.5
7.8	-37.0	92.0
4.0	-32.0	90.0
1.0	-28.0	84.0
-0.8	-21.5	82.0
-1.2	-14.5	76.0
-7.0	-12.5	77.7
-11.5	-14.0	77.5
-32.3	-14.0	80.0
-34.2	-14.8	80.0
-54.2	-2.0	65.0

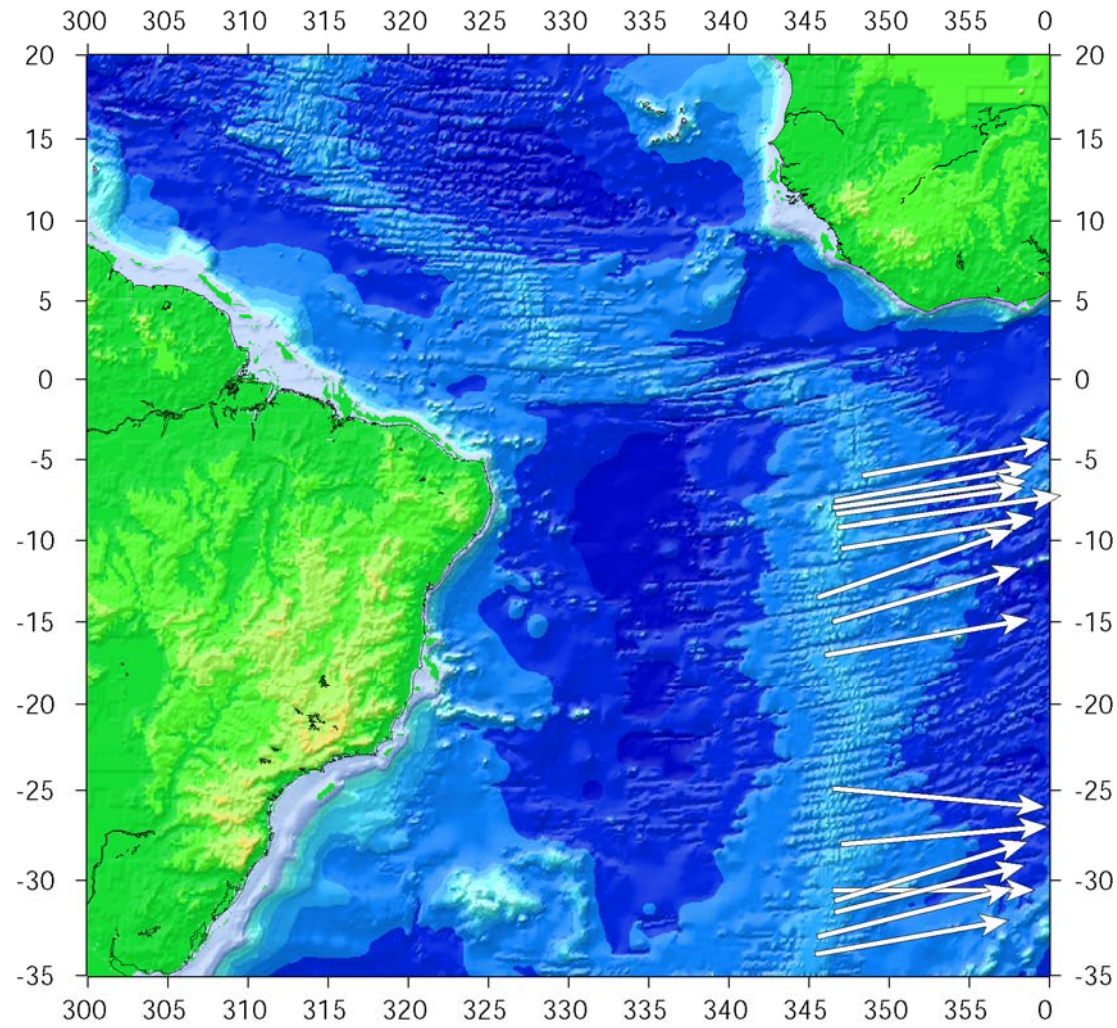


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Geological model : real data

Spreading rates

lon, lat, rate, az
-6.0 -11.7 33 10
-7.6 -13.4 35 10
-8.0 -13.5 34 8
-8.4 -13.3 33 8
-9.2 -13.2 39 8
-10.5 -13.0 34 9
-13.5 -14.5 36 19
-15.0 -13.5 34 16
-17.0 -14.0 36 10
-24.9 -13.5 37 -5
-28.0 -13.0 36 5
-30.5 -13.5 35 0
-31.1 -13.4 35 17
-31.7 -13.4 34 14
-33.0 -14.5 35 14
-33.9 -14.6 34 10
-38.5 -17.0 36 10
-40.0 -16.0 36 5
-42.0 -16.0 32 5
-43.0 -16.0 35 5
-54.2 -1.3 28 25
-54.5 -1.1 30 25



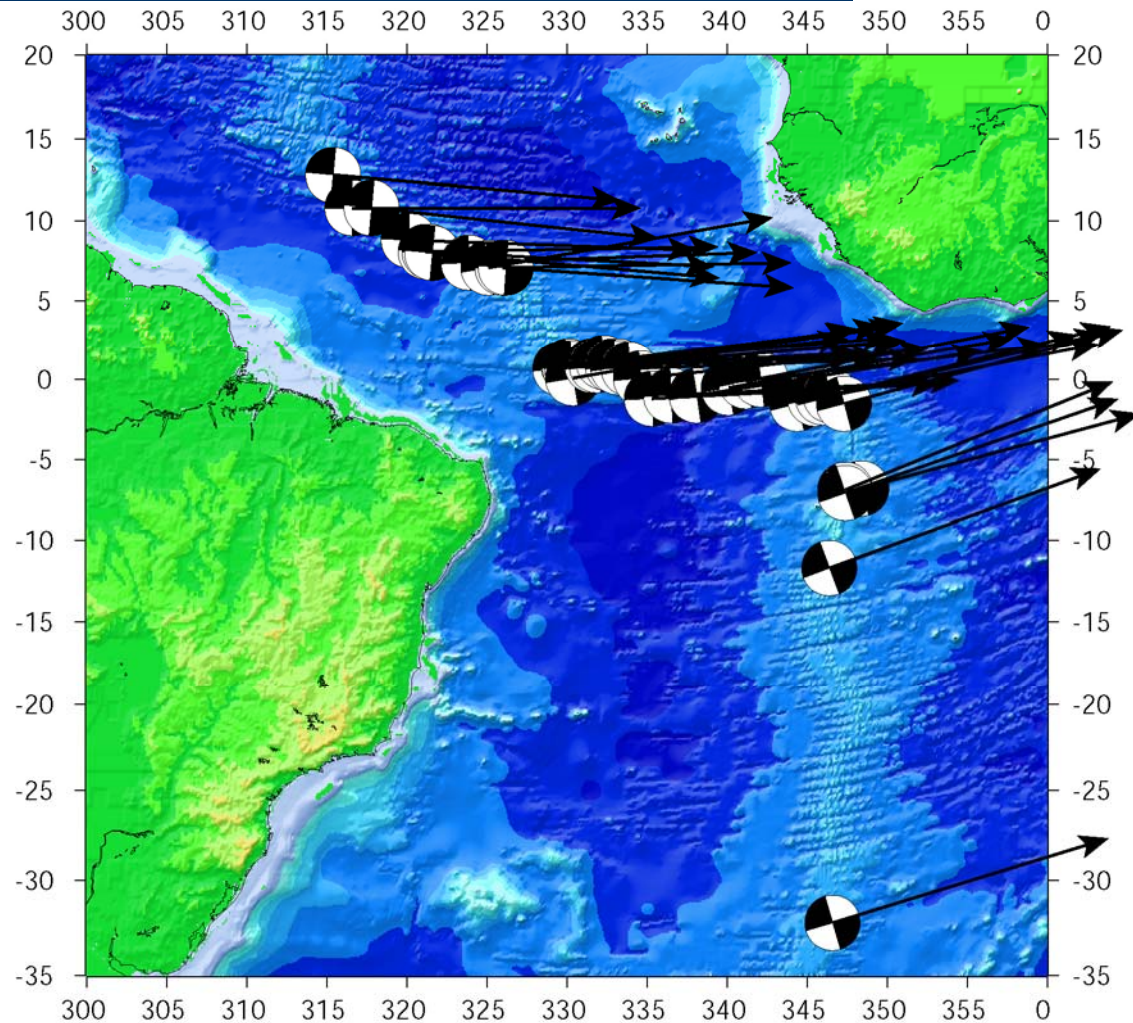
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Geological model : real data

Slip vector azimuths

Lon	lat	azimut
12.8	-44.6	95.0
10.8	-43.4	90.0
10.8	-42.2	96.0
8.8	-39.9	92.0
8.1	-38.8	93.0
8.1	-38.5	89.0
8.0	-38.4	95.0
7.4	-36.1	88.0
7.1	-34.9	80.0
7.1	-34.0	89.0
7.1	-33.8	94.0
0.7	-30.4	84.0
0.9	-29.9	83.0
0.8	-29.8	88.0
0.8	-29.7	87.0
0.1	-29.6	80.0
0.9	-28.4	88.0
0.9	-28.1	82.0
1.1	-27.7	85.0
0.9	-27.1	85.0
0.9	-27.1	82.0
0.9	-26.8	85.0
0.8	-26.8	81.0
0.7	-26.1	88.0
0.1	-25.3	84.0
-1.2	-24.7	87.0
-1.0	-23.5	87.0
-1.0	-21.9	81.0

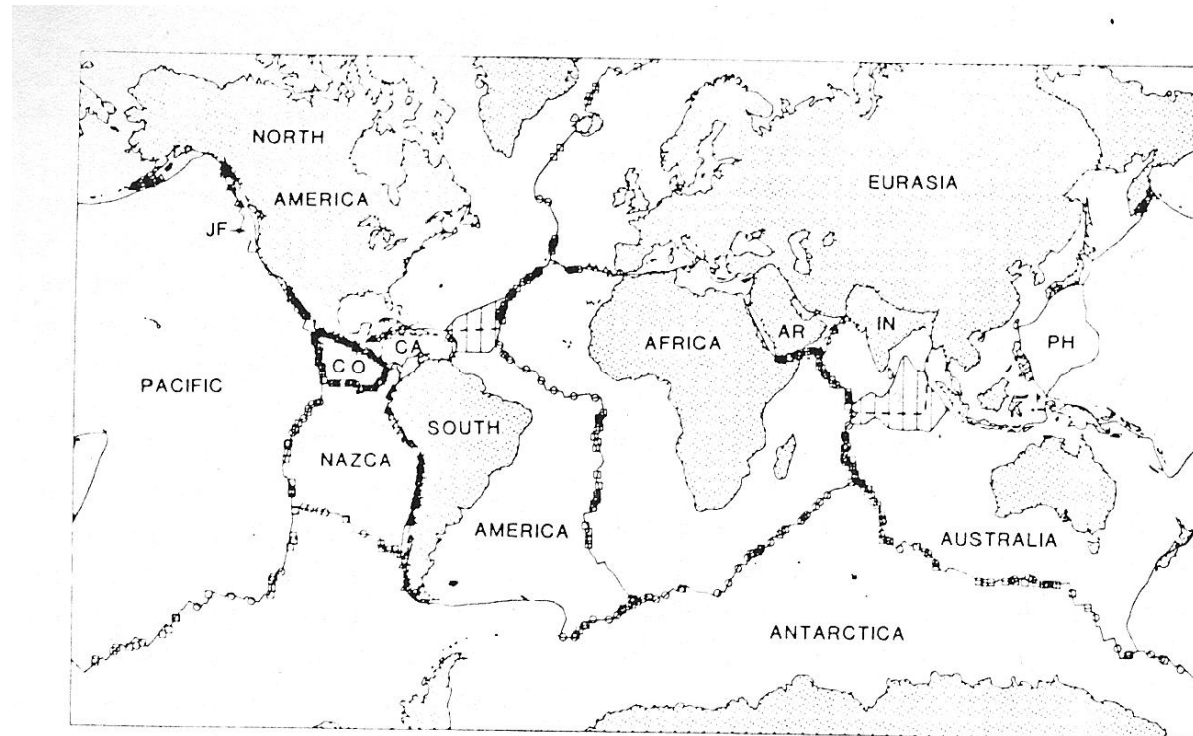
Lon	lat	azimut
-0.5	-19.9	80.0
-0.1	-18.8	79.0
-0.0	-17.9	83.0
-1.5	-15.6	76.0
-1.2	-14.5	79.0
-1.1	-14.0	77.0
-1.0	-13.5	76.0
-1.5	-12.7	75.0
-6.8	-11.6	75.0
-6.9	-12.6	68.0
-7.1	-12.6	71.0
-11.7	-13.6	70.0
-32.2	-13.4	73.0
-35.8	-16.0	76.0
-35.5	-16.1	81.0
-47.6	-12.9	76.0
-46.9	-10.8	85.0



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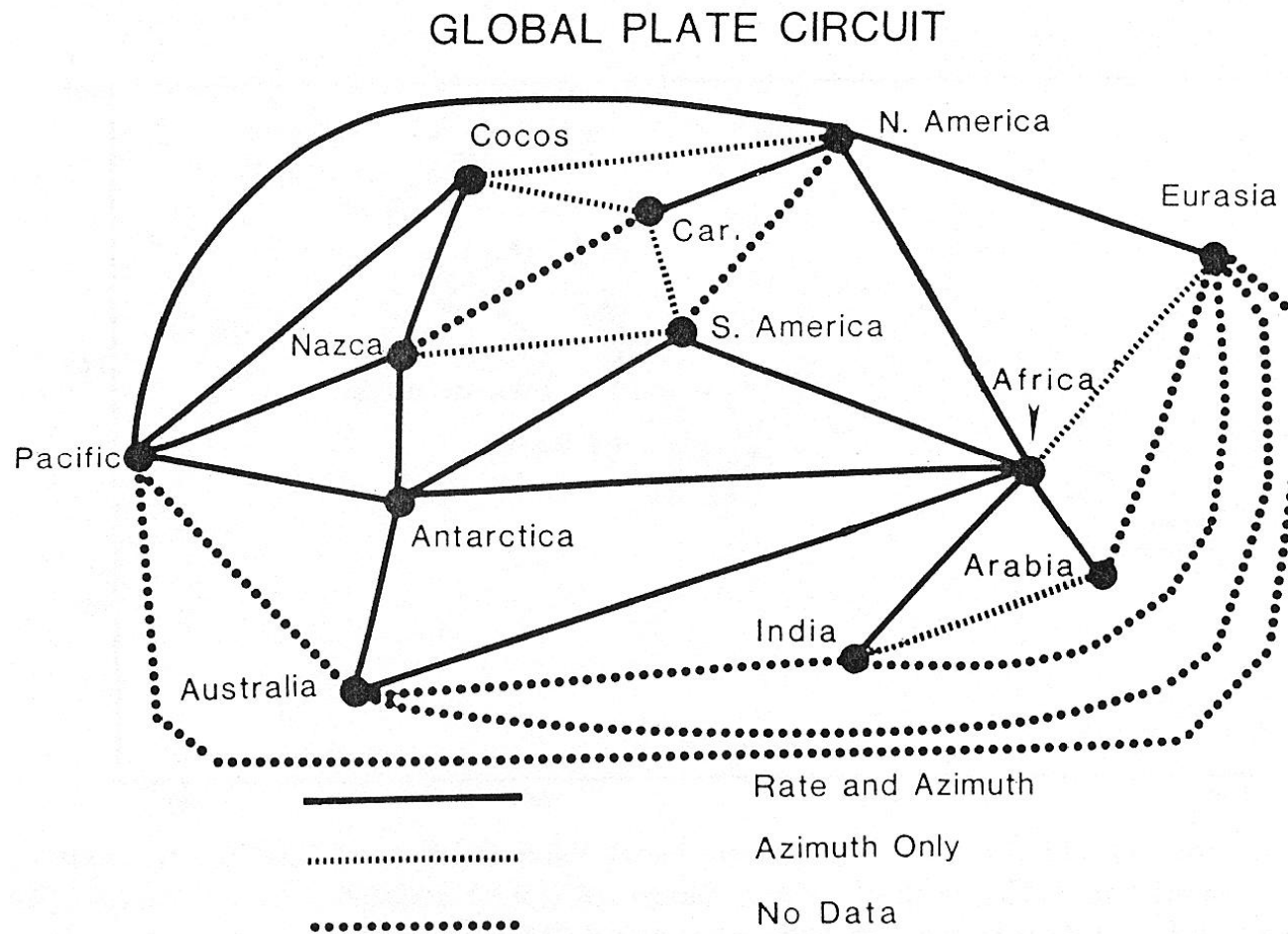
Geological model : Nuvel-1A, Demets et al., 1990

Current plate motions, Geophys. Journal. Int., 101, 425-478, 1990

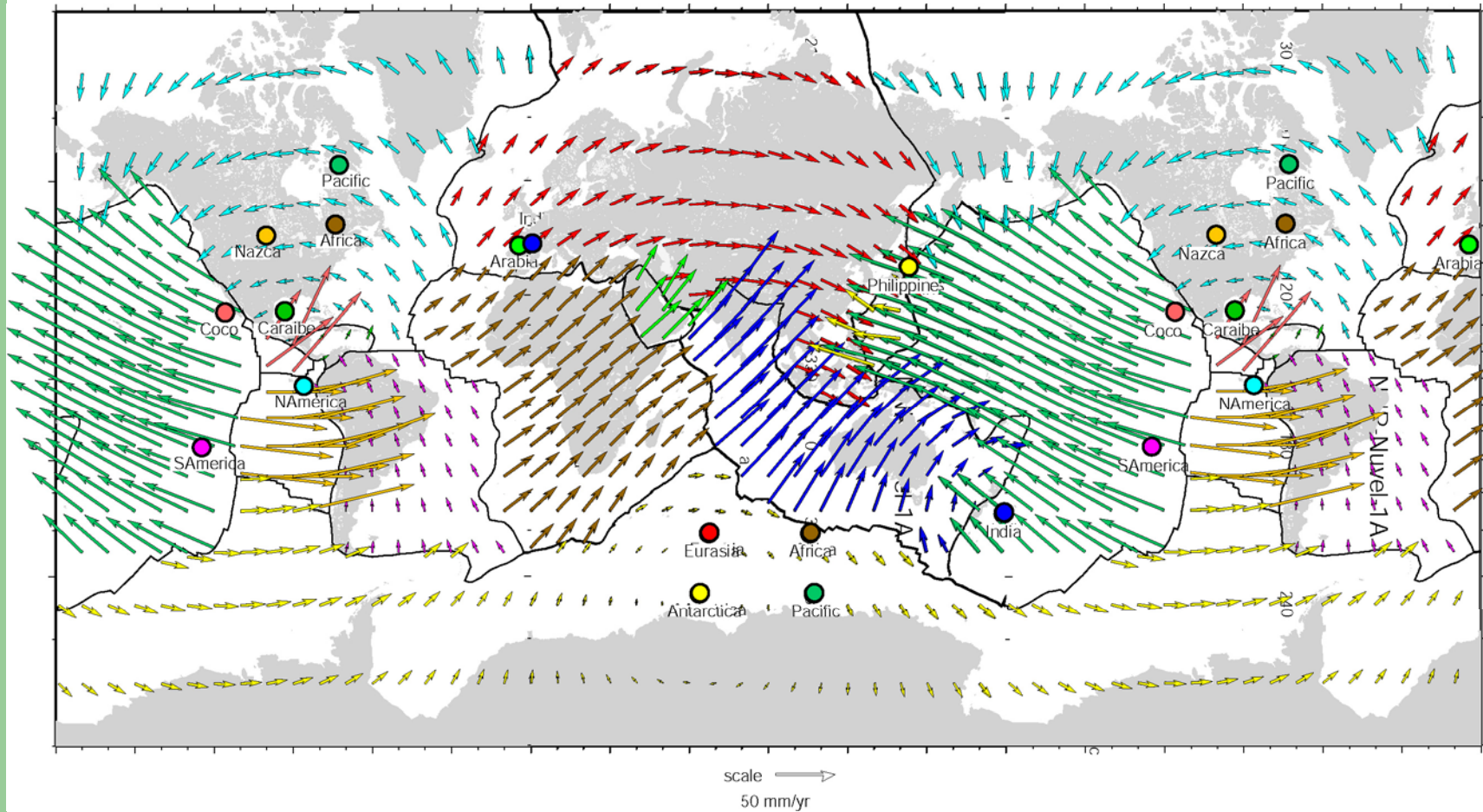


Around 1200 slip vector azimuth, transform fault orientations and spreading rates are compiled in one model for plate motion

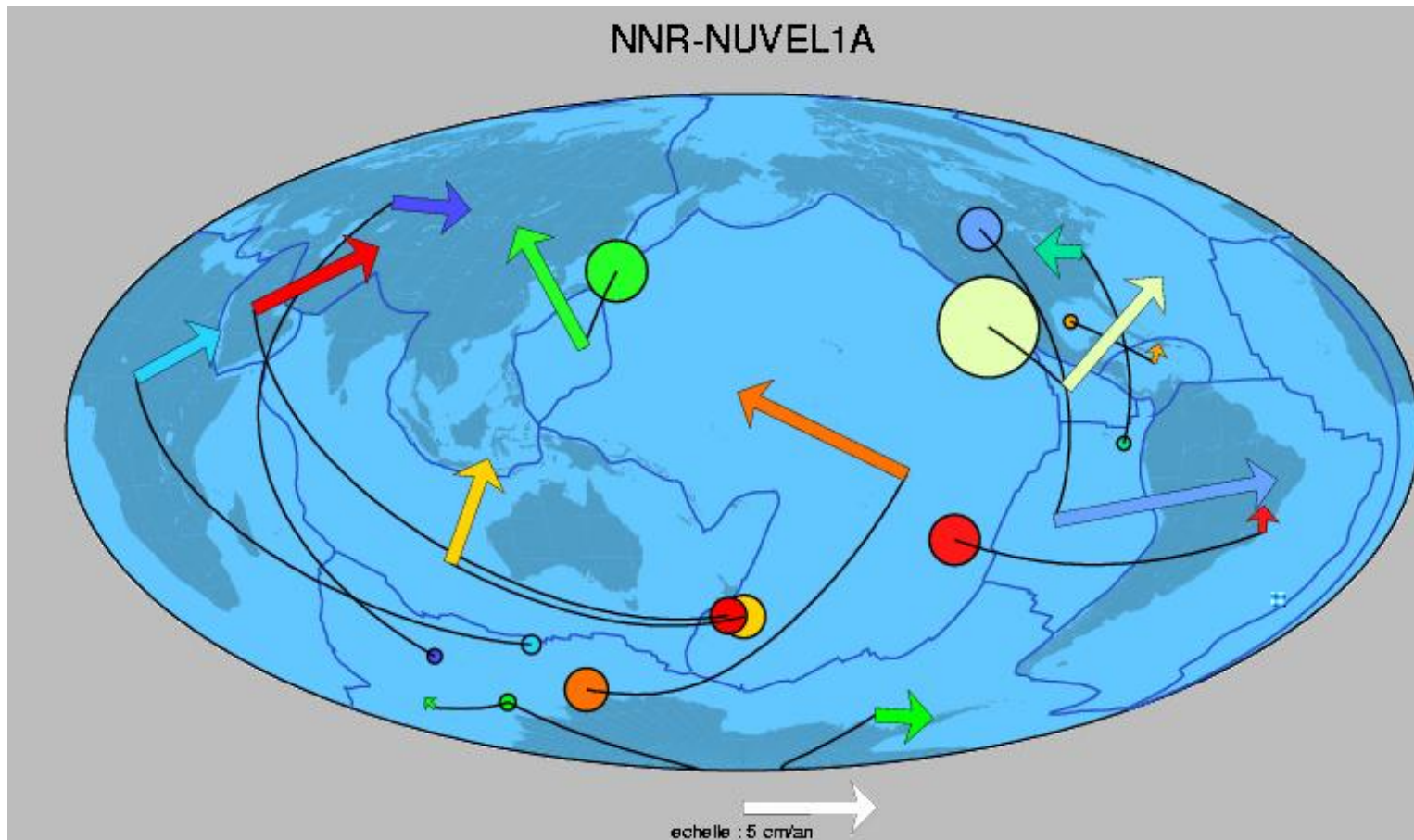
Geological model : closure circuit



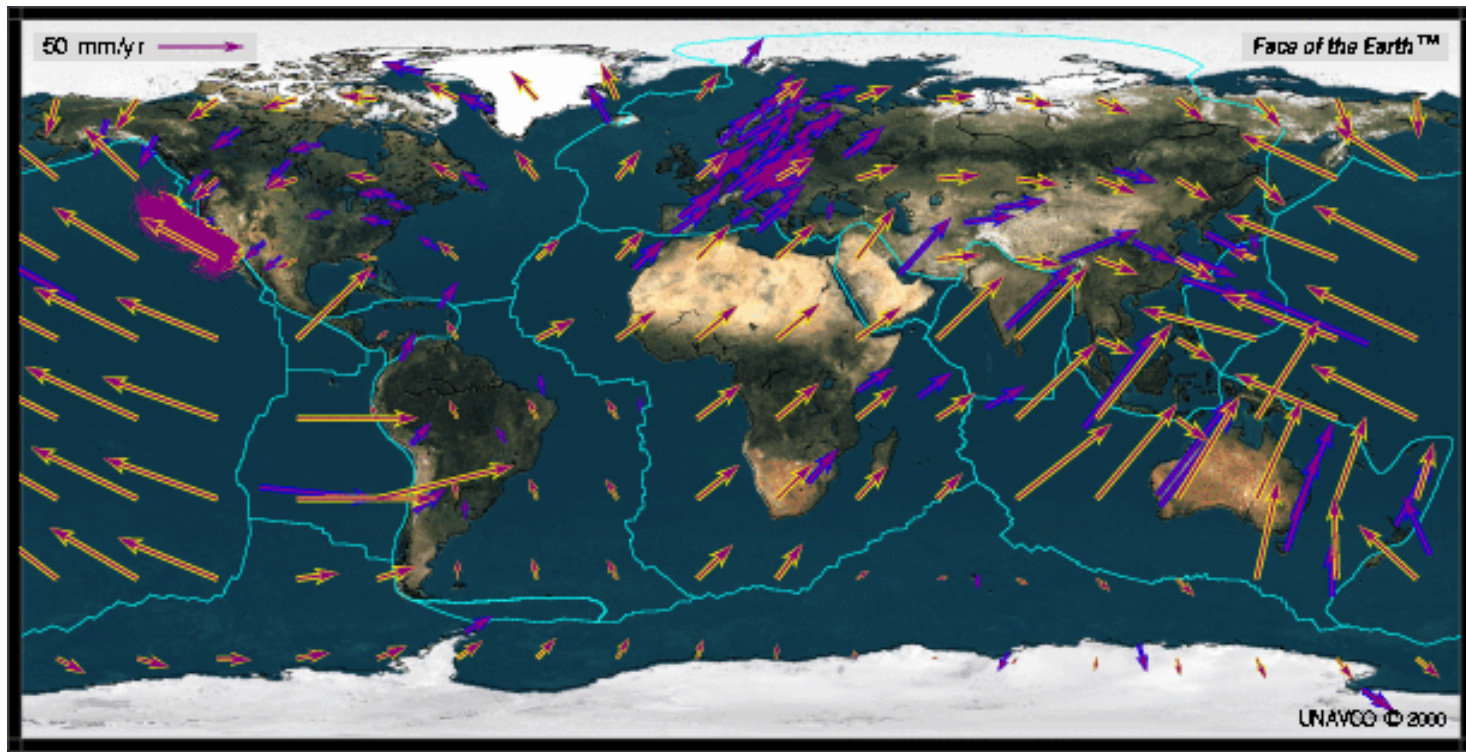
NNR-Nuvel-1A : velocities



NNR-Nuvel-1A : poles



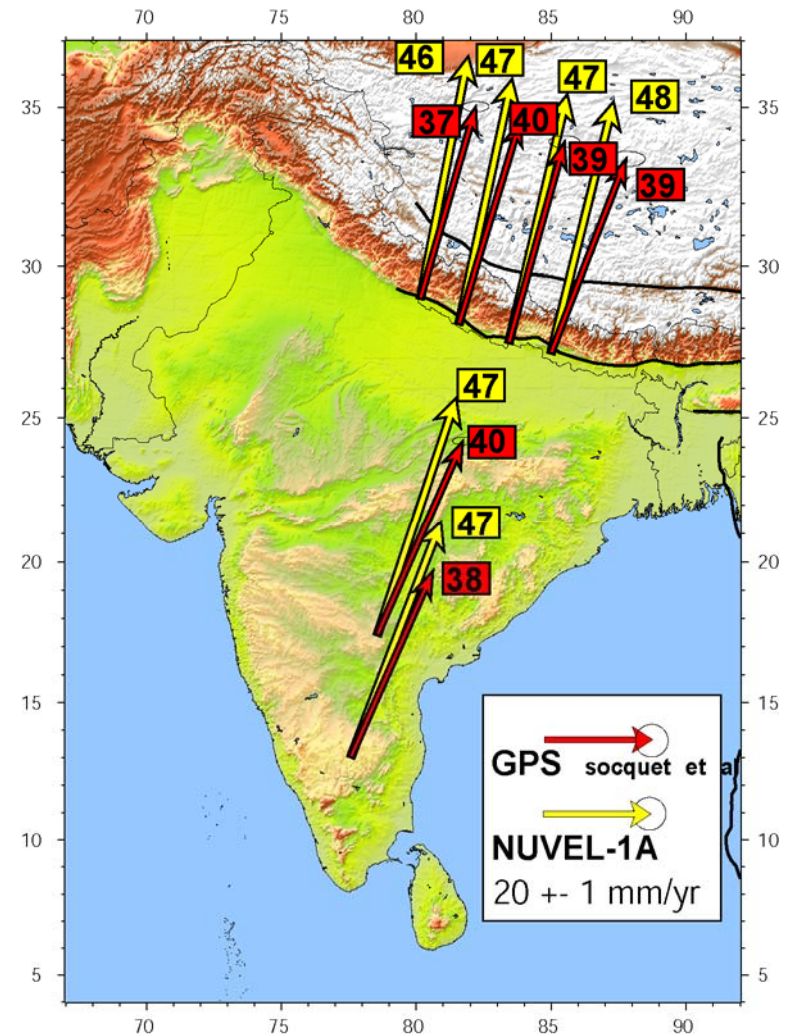
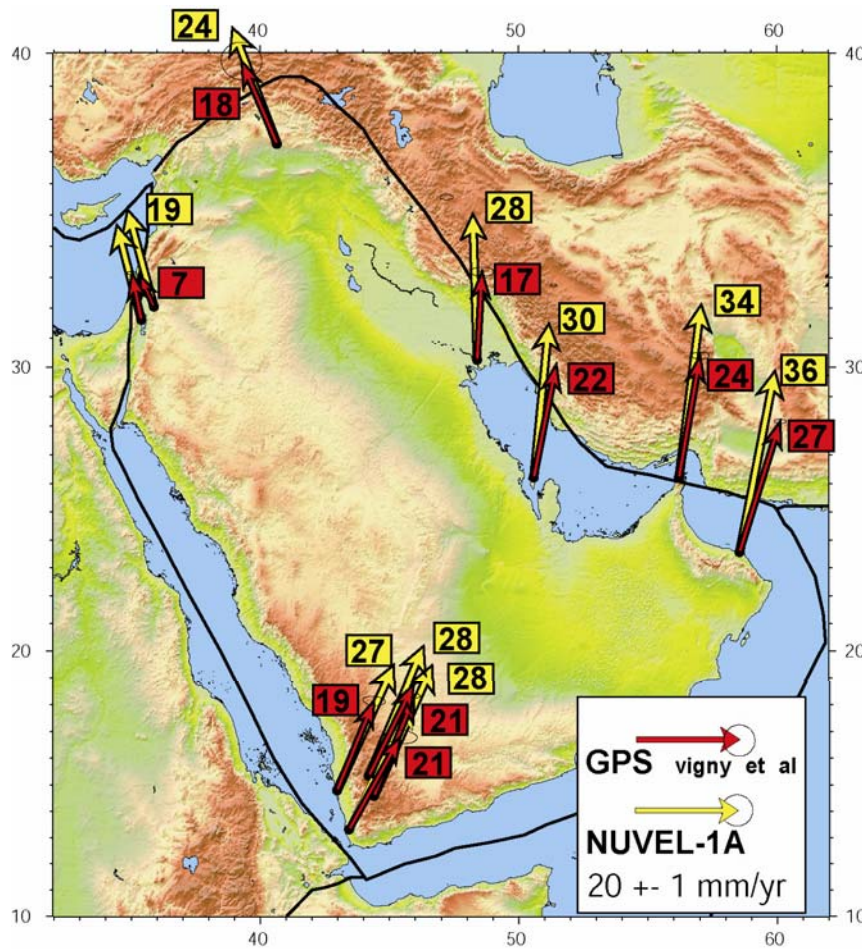
GPS VEL solution



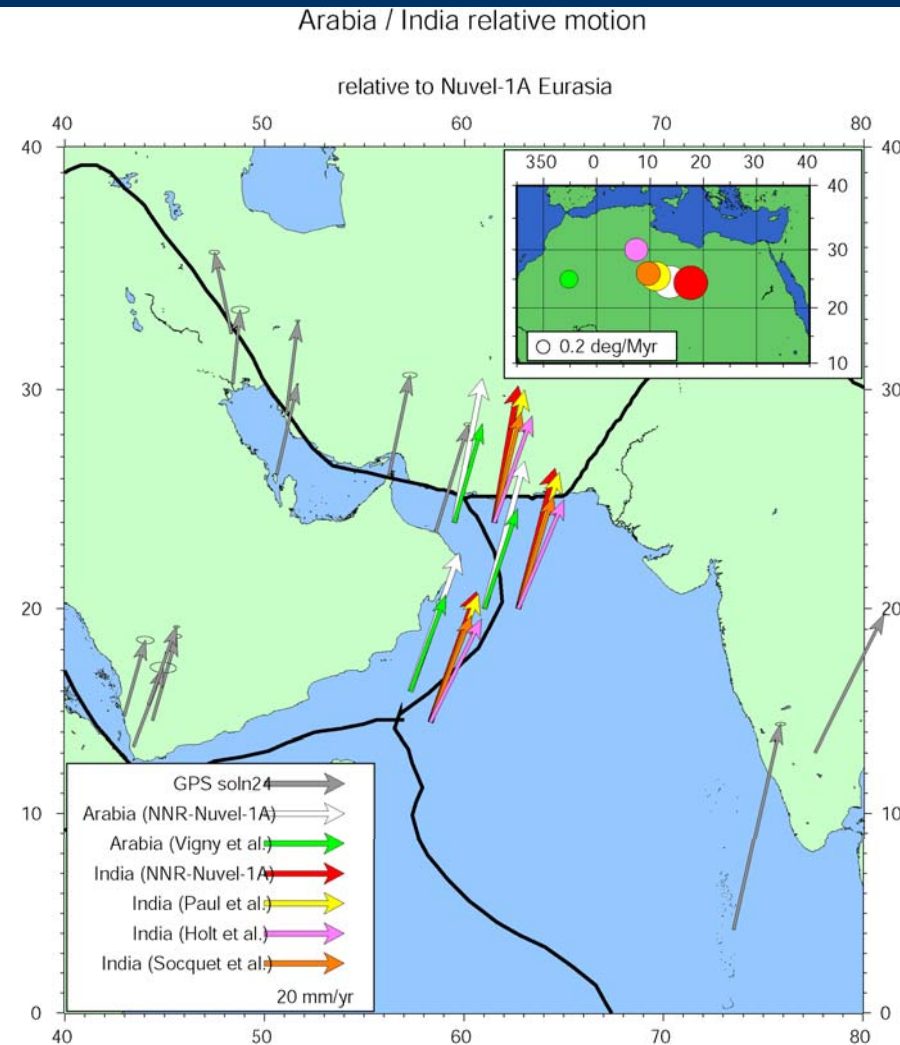
Nuvel-1A (yellow) – GPSVEL (violet)

Good match with “geological” velocities: 1 cm/yr = 10 km in 1 million year), but...

GPS finds Arabia and India are slower than expected

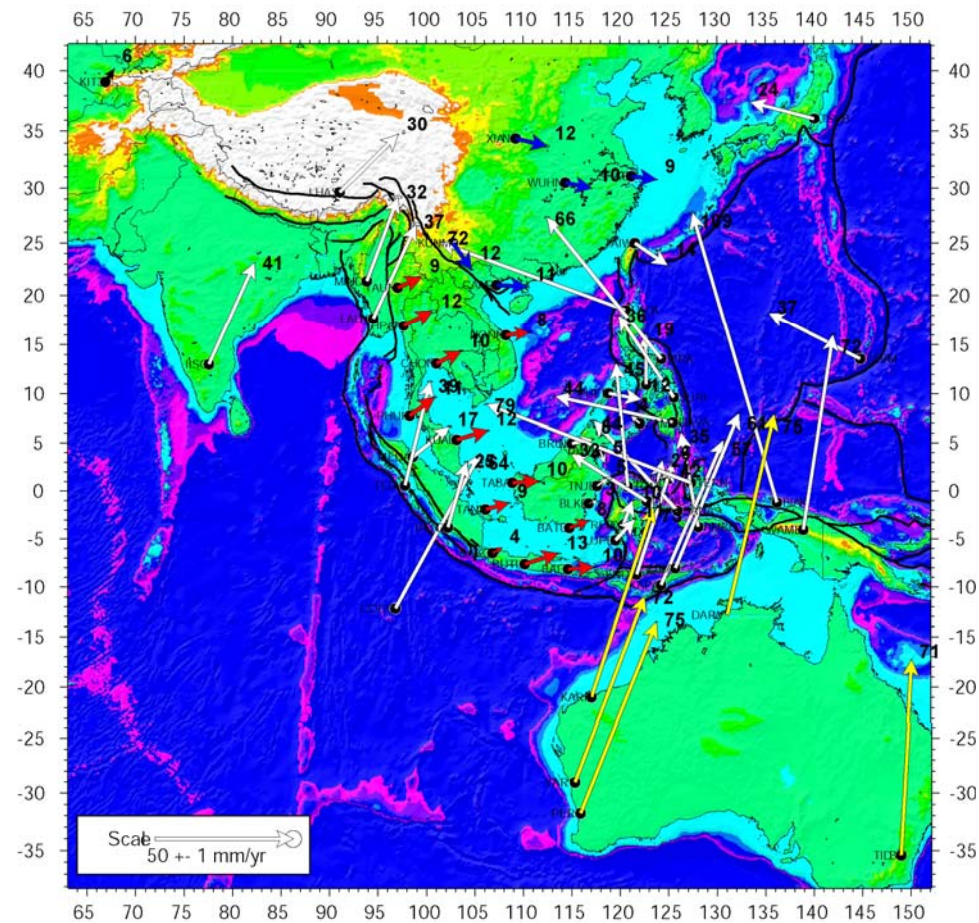


Arabia India relative motion



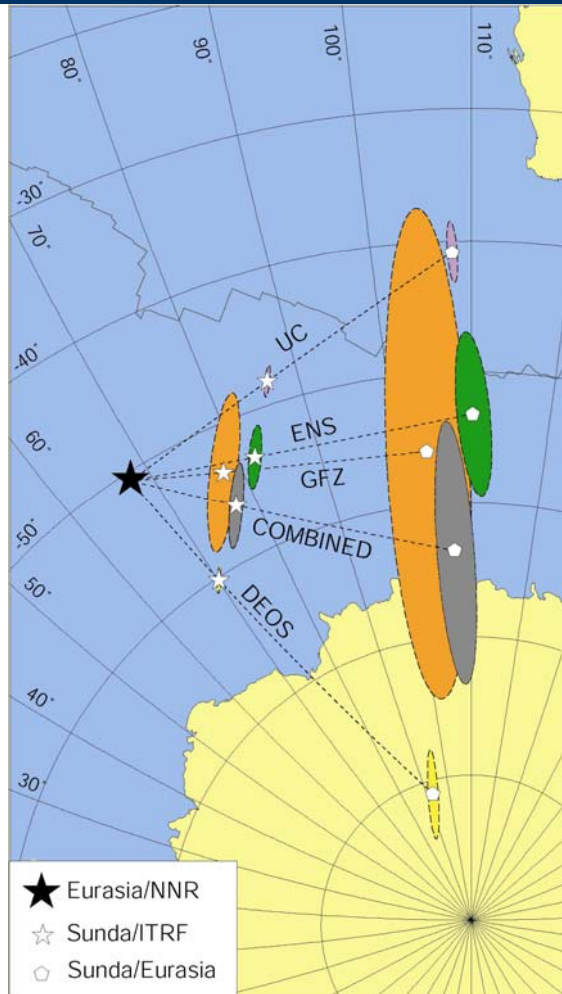
Rigid Sundaland

South-East ASIA 94-96-98-00 (ITRF2000)
ENS solution / NNR-Nuvel-1A Eurasia (50.6,-112.4,0.23)

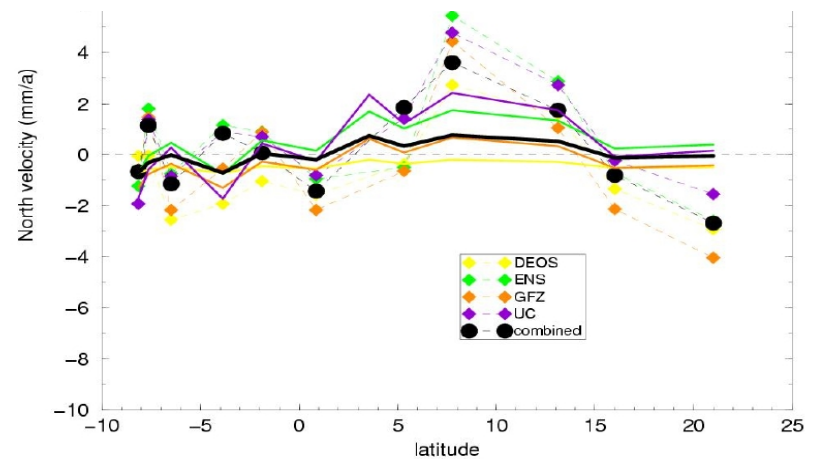
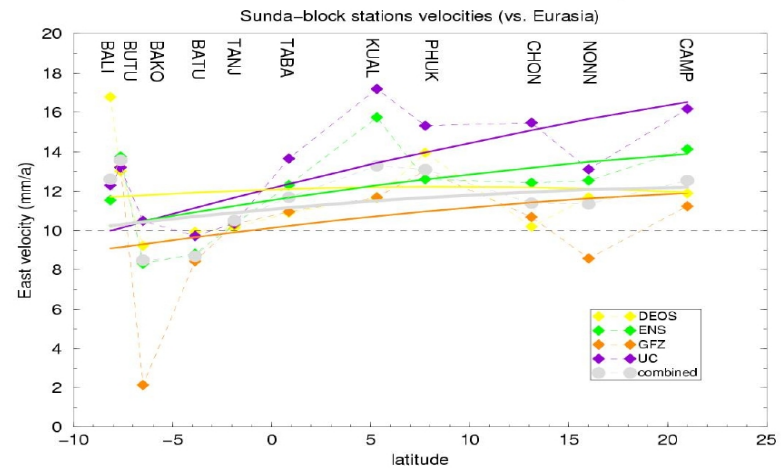


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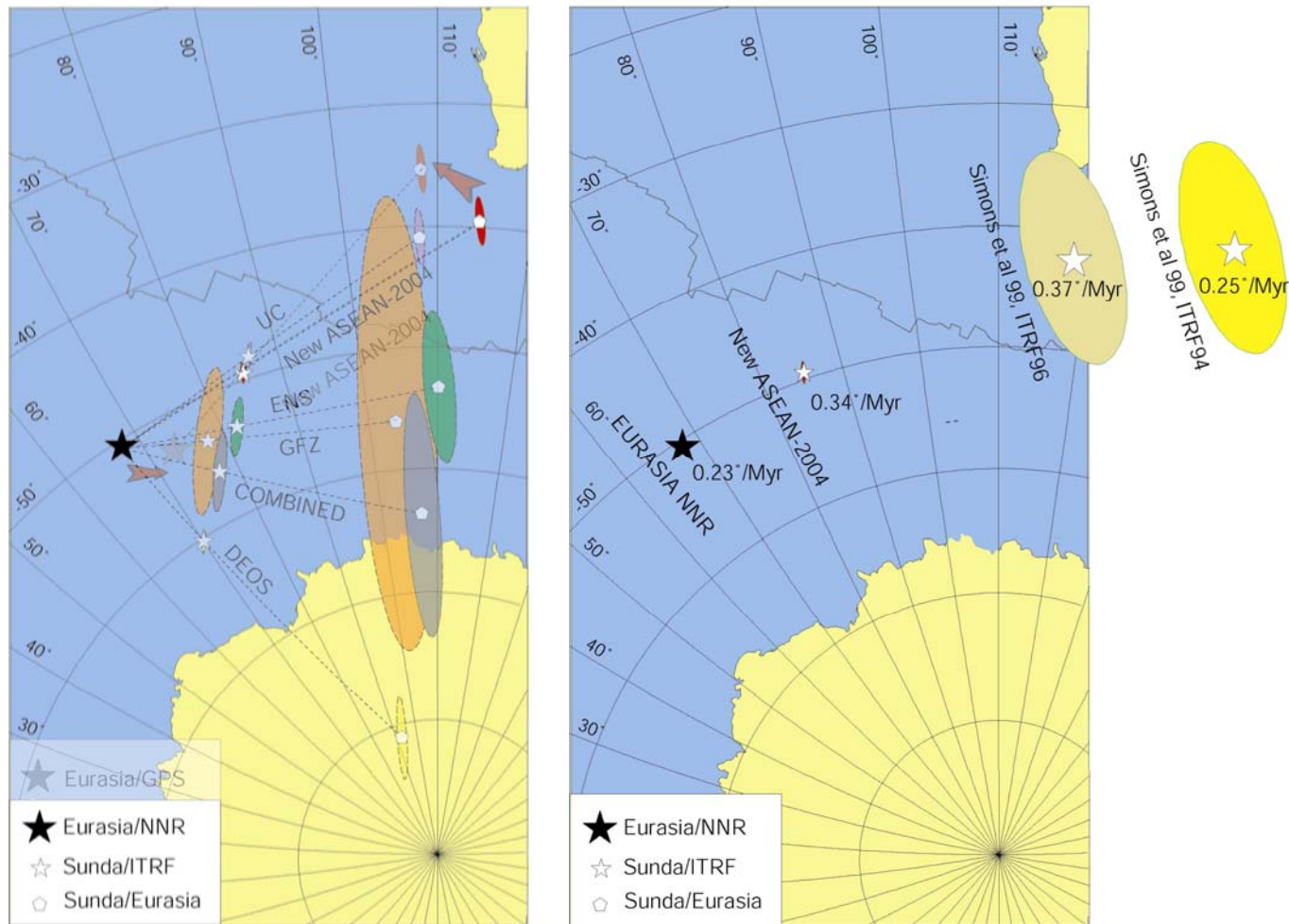
GEODYSSEA poles



GEODYSSEA 94-96-98 – solutions comparisons



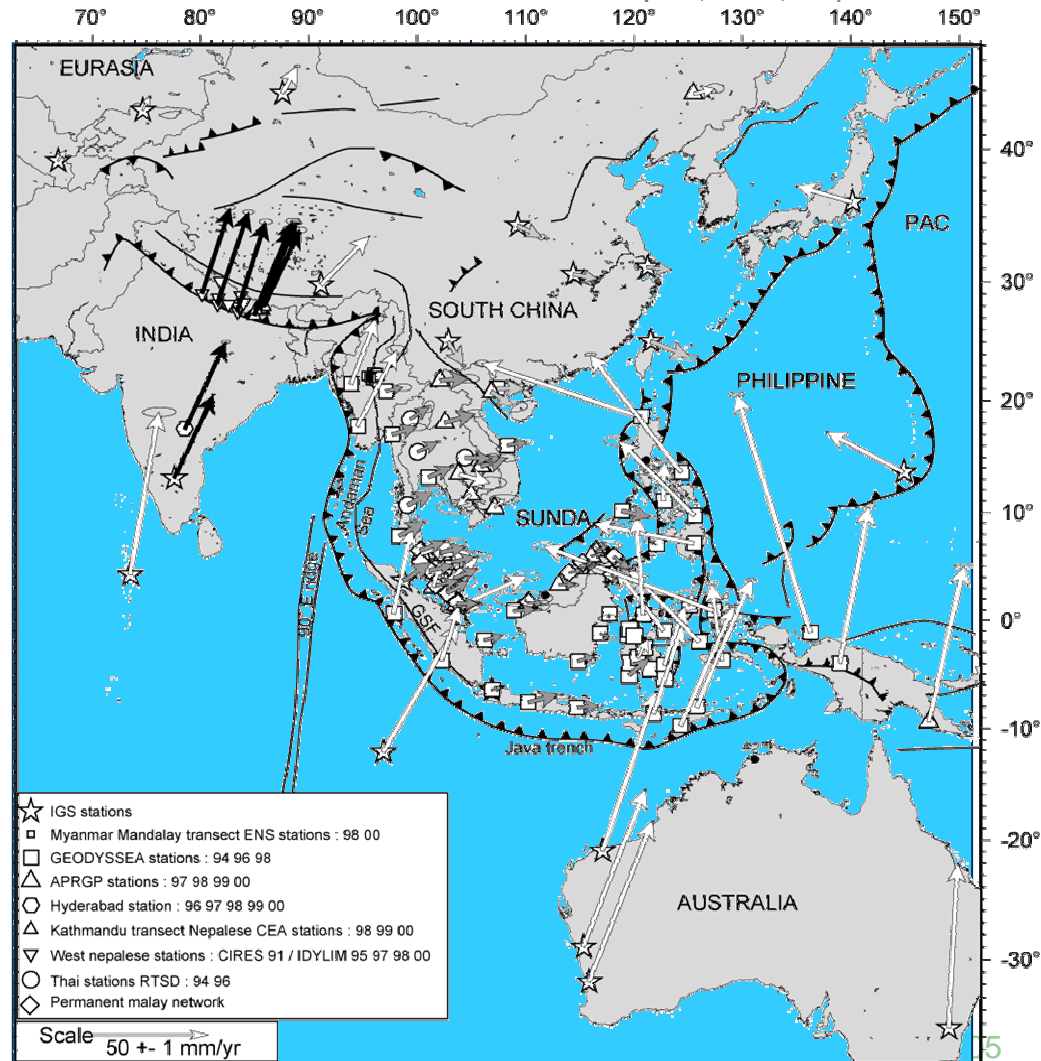
Older GEODYSSSEA poles



New ASEAN solution (Simons and Socquet, submitted)

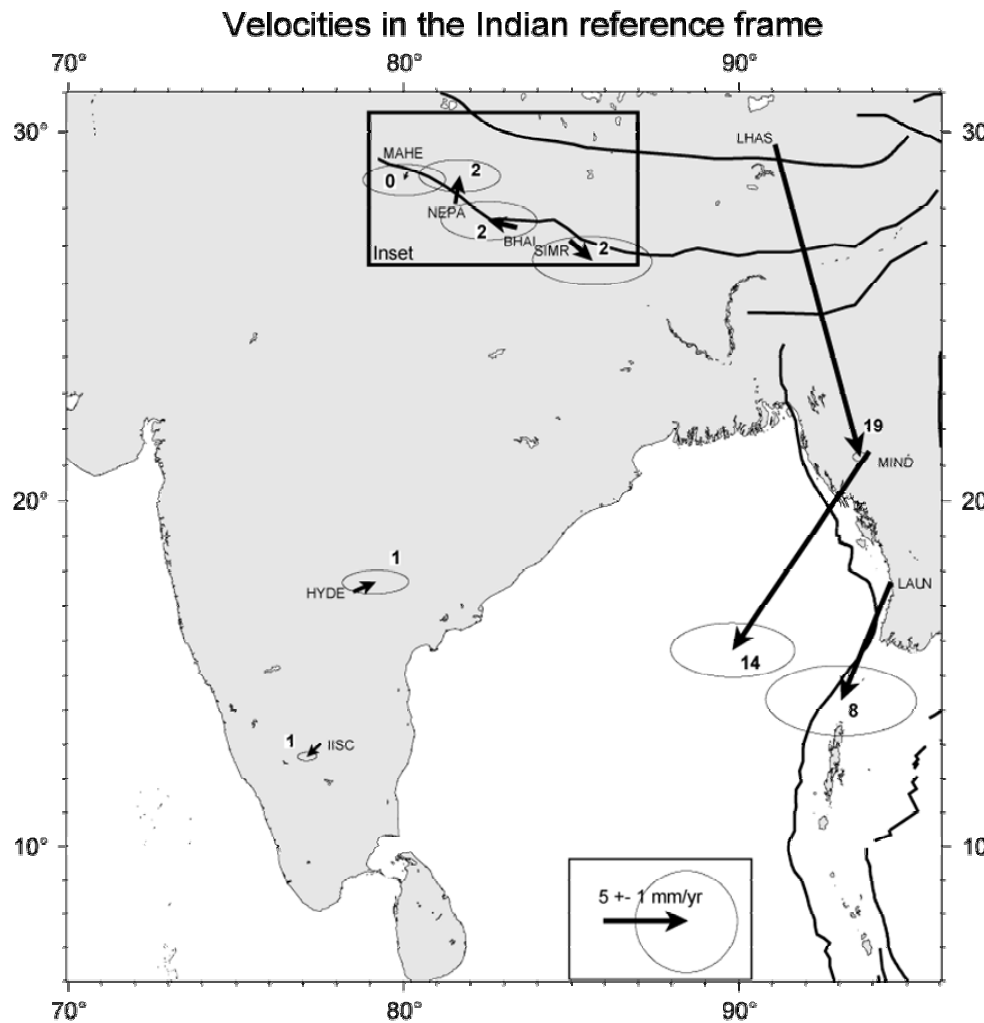
South-East ASIA 91-94-95-96-97-98-99-00 (ITRF2000)

ENS solution / NNR-Nuvel-1A Eurasia (50.6, -112.4, 0.23)

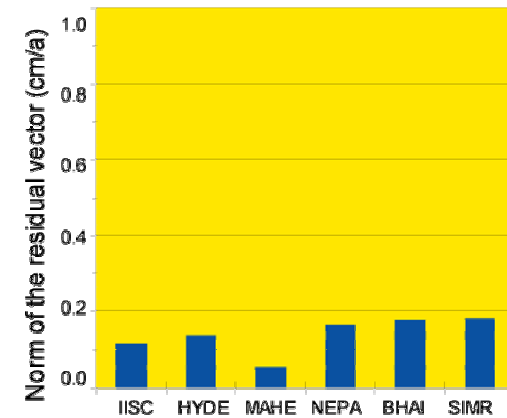


120 sites measured over a decade

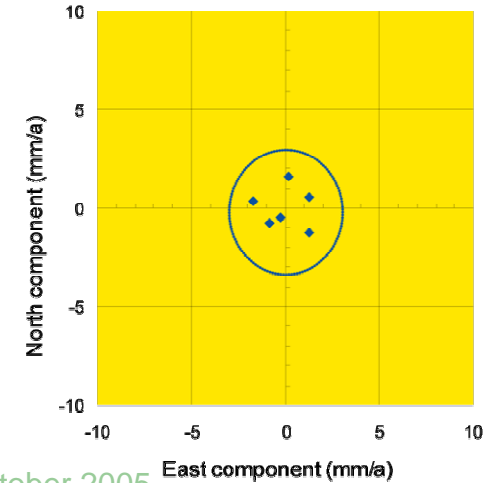
Rigidity of India



BEST FIT RESIDUALS

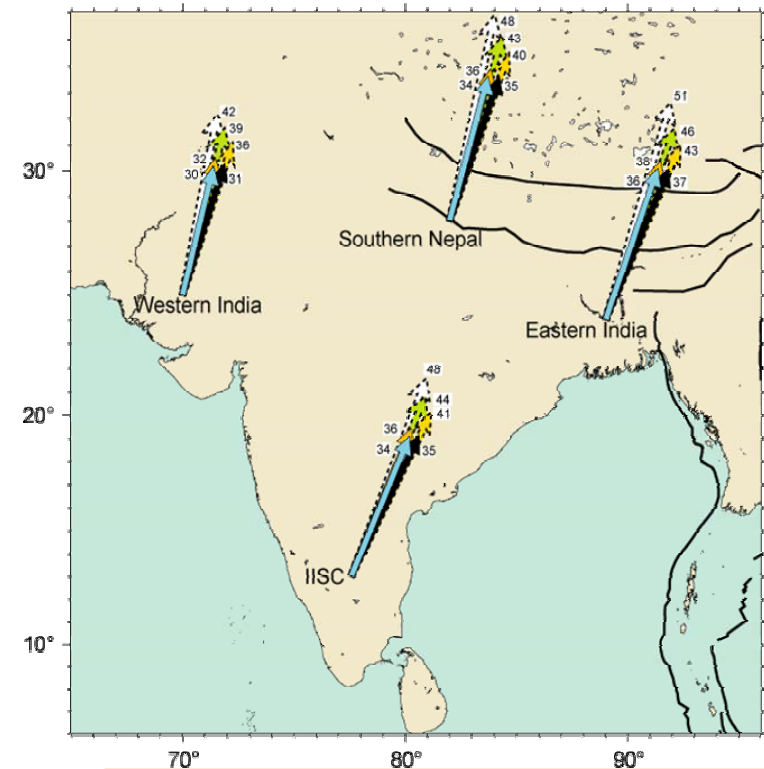
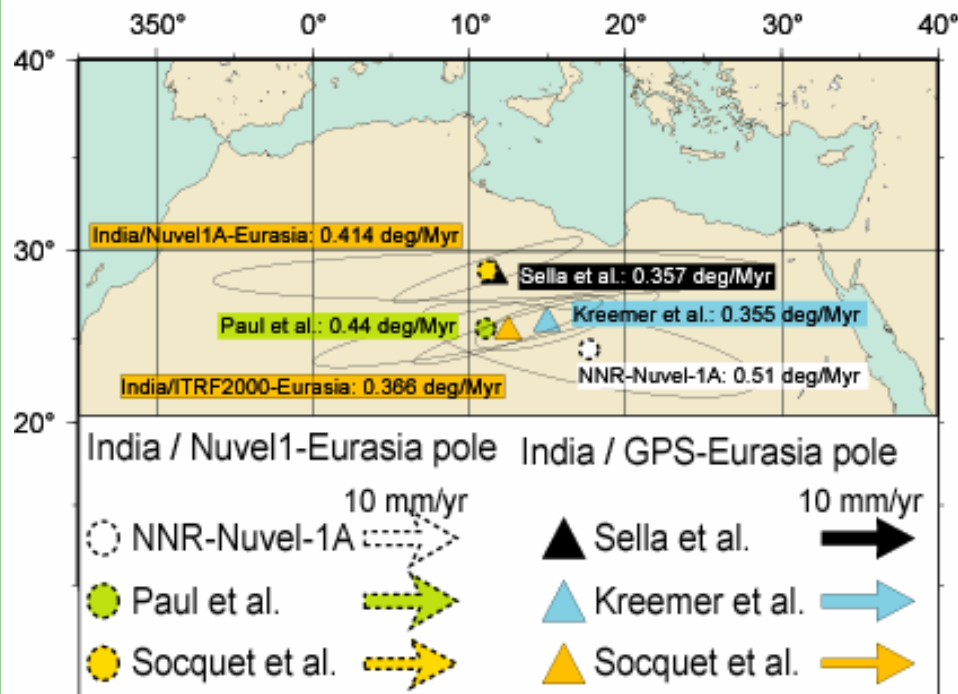


RESIDUAL VECTOR COMPONENTS



India-Eurasia motion

motion from different studies

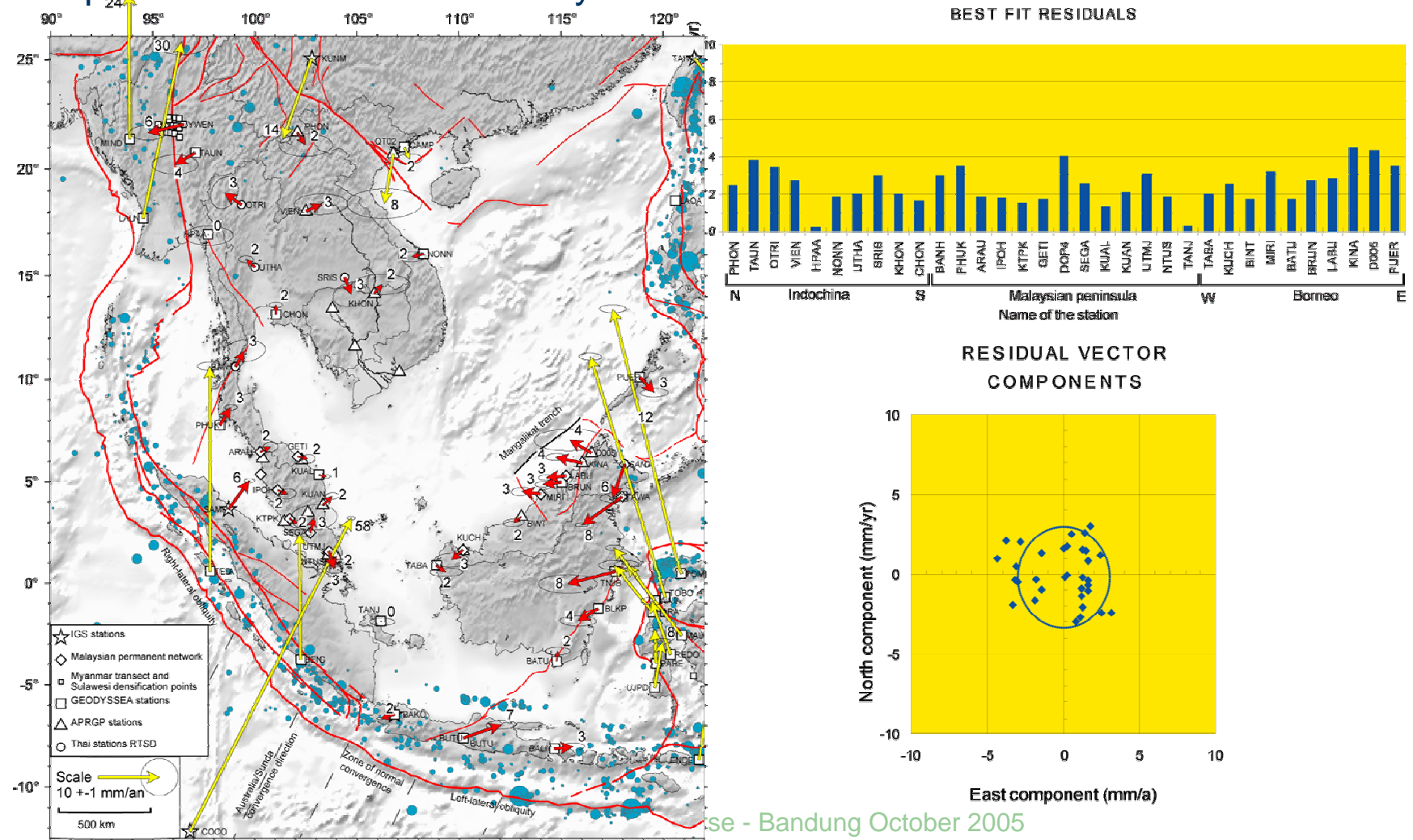


3.5 cm/yr

Instead of **5 cm/yr**
we thought 10 years ago

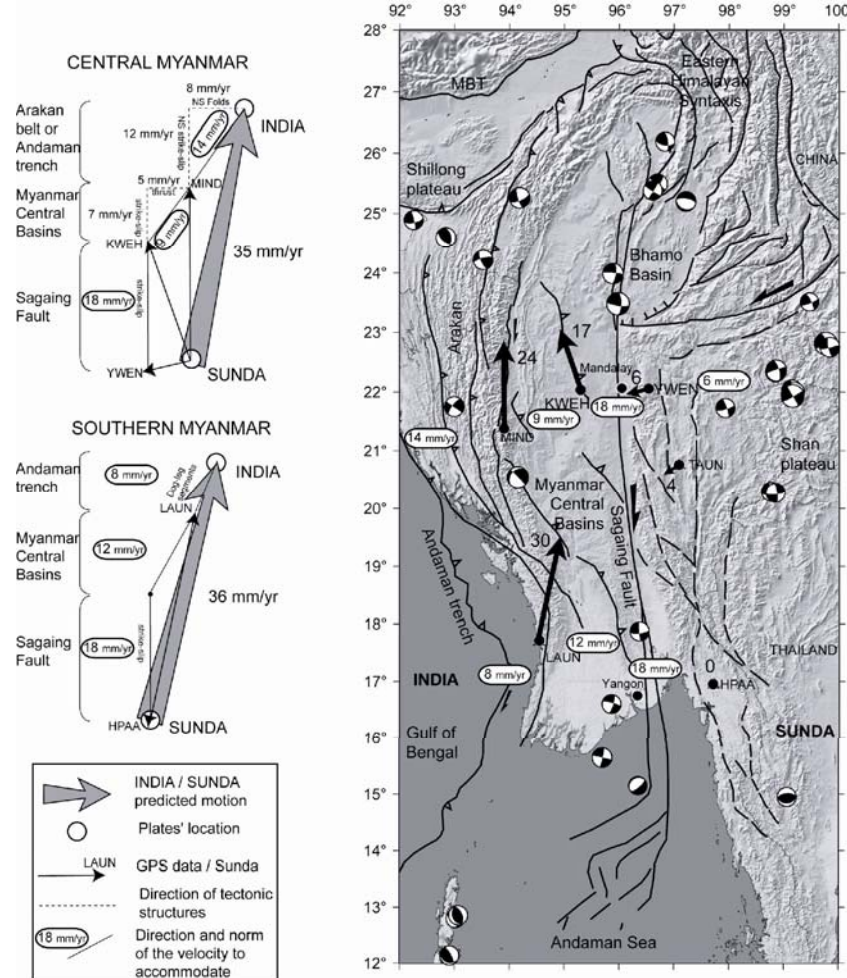
ASEAN Residual velocities

Pole positions **don't** matter ... Only **residual velocities** do



India/Sunda relative motion

Pole positions **don't** matter...only **predicted motions on plate boundary do**



Strain rate and rotation rate tensors (1)

To assess plate deformation :

1. Look at station velocity residuals
2. Compute strain rate and rotation rate tensors

$$\text{Strain} = \frac{\text{Velocity}}{\text{Distance}} = \frac{\text{mm/yr}}{\text{km}} = \% / \text{yr}$$

$$\text{Matrix tensor notation : } S_i^j = d(V_i) / d(x_j) = \begin{bmatrix} d(V_x) / d(x) & d(V_x) / d(y) \\ d(V_y) / d(x) & d(V_y) / d(y) \end{bmatrix}$$

$$\text{Theory says : } [S] = [E] + [W]$$

Symmetrical Antisymmetrical
Strain rate rotation rate

Strain rate and rotation rate tensors (2)

$$[E] = \frac{1}{2} ([S] + [S]^T) = \begin{bmatrix} E_{11} & E_{12} \\ E_{12} & E_{22} \end{bmatrix} \quad [W] = \frac{1}{2} ([S] - [S]^T) = \begin{bmatrix} 0 & W \\ -W & 0 \end{bmatrix}$$

[E] has 2 Eigen values : \mathcal{E}_1 , \mathcal{E}_2

\mathcal{E}_1 and \mathcal{E}_2 are extension/compression along principal direction defined by angle θ (defined as angle between \mathcal{E}_2 direction and north)

$$\mathcal{E}_1 = E_{11} \cos^2\theta + E_{22} \sin^2\theta - 2 E_{12} \sin\theta \cos\theta$$

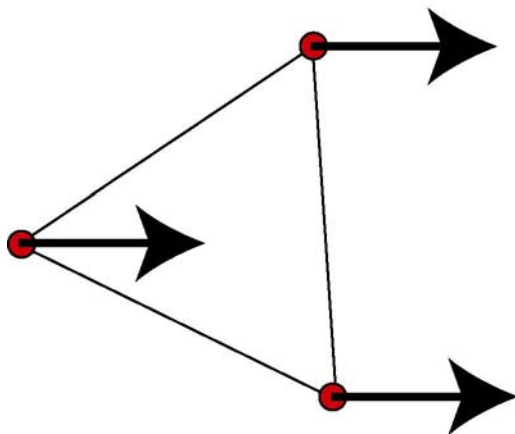
$$\mathcal{E}_2 = E_{11} \sin^2\theta + E_{22} \cos^2\theta - 2 E_{12} \sin\theta \cos\theta$$

Strain rate and rotation rate tensors (3)

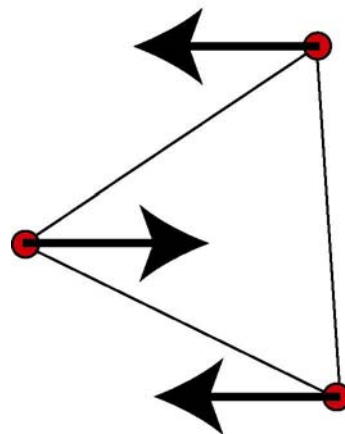
Minimum requirement to compute strain and rotation rates is :

3 velocities (to allow to determine **3 values** ϵ_1 , ϵ_2 , and W)

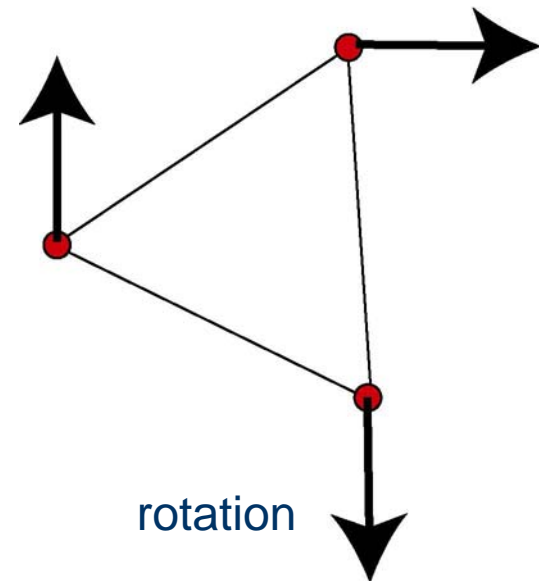
Therefore we can compute strain rate and rotation rate within any polygon, the minimum polygon being a **triangle**



No deformation



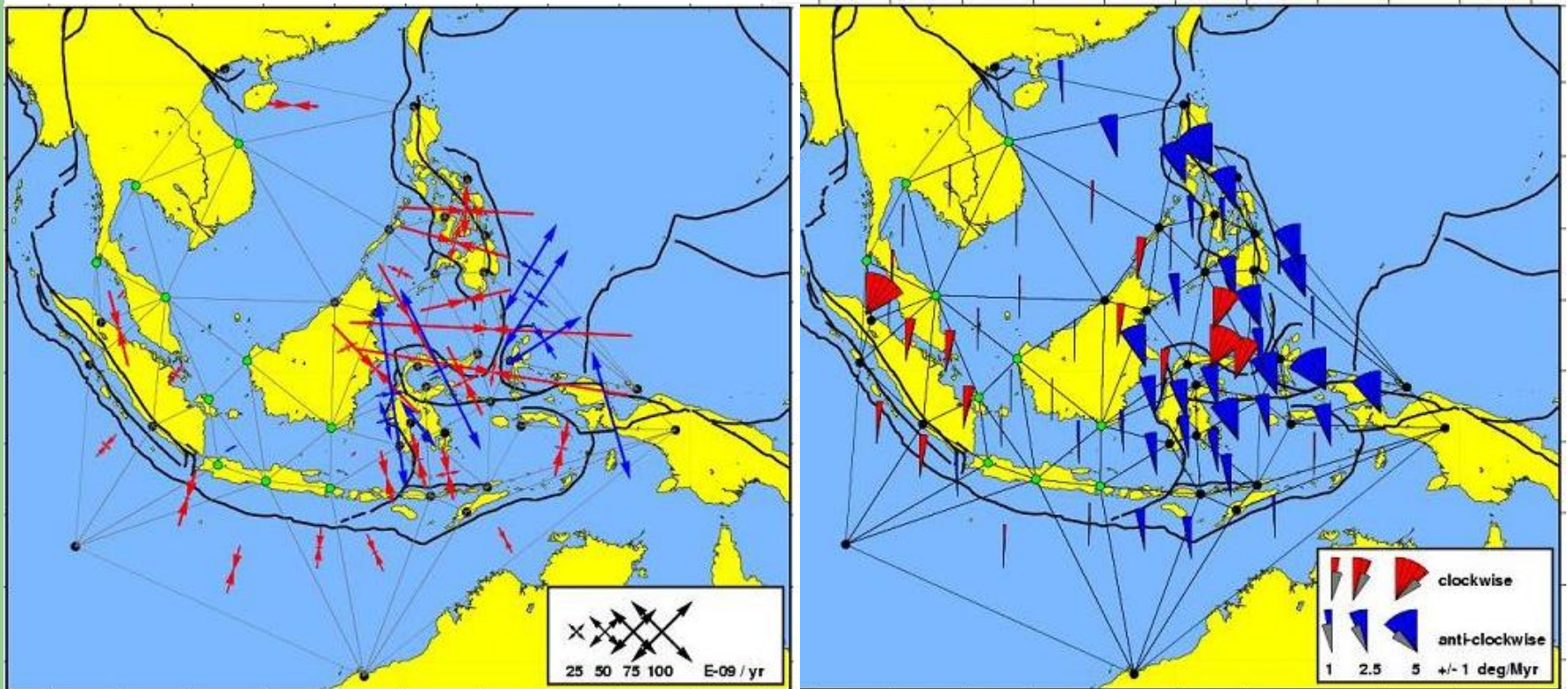
compression



rotation

Strain and rotations are **unensitive** to reference frame

Strain and rotation in GEODYSSSEA network



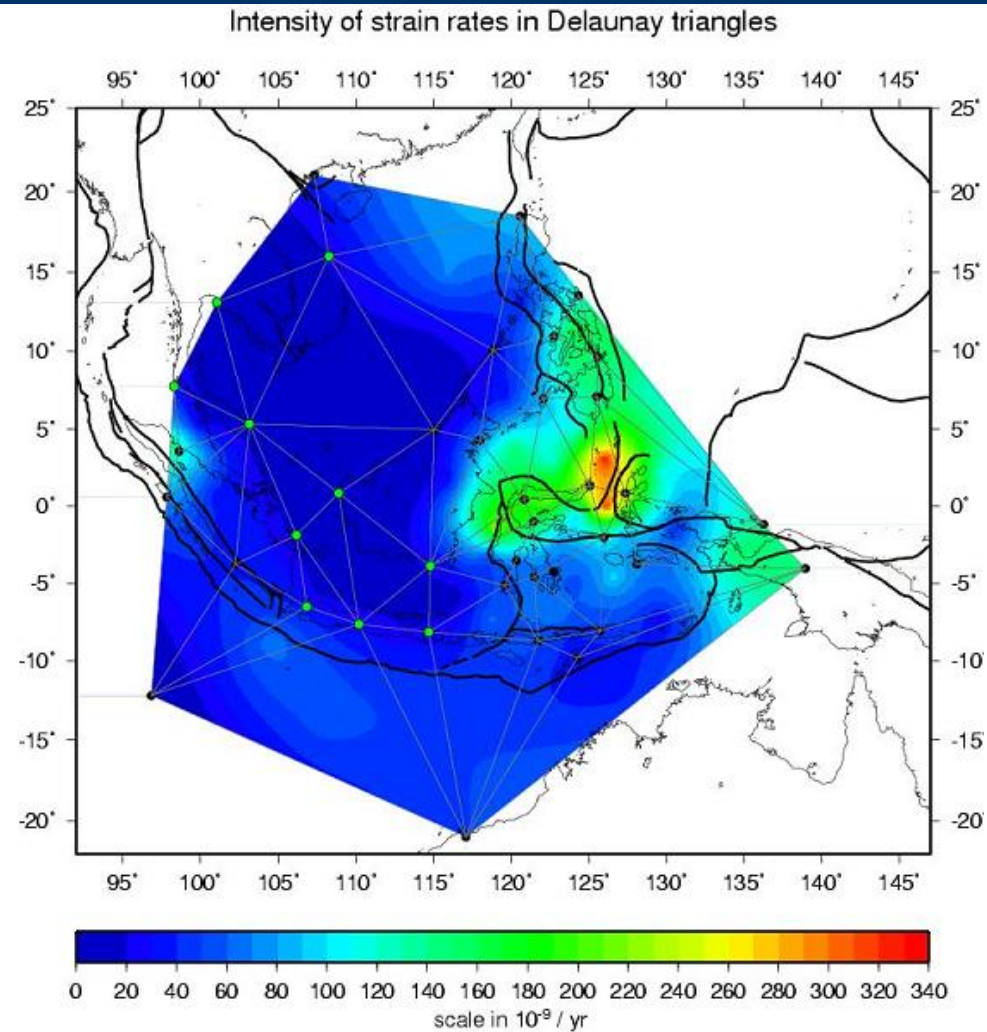
Strains :

extension/**compression**/**strike-slip**

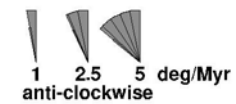
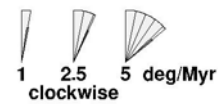
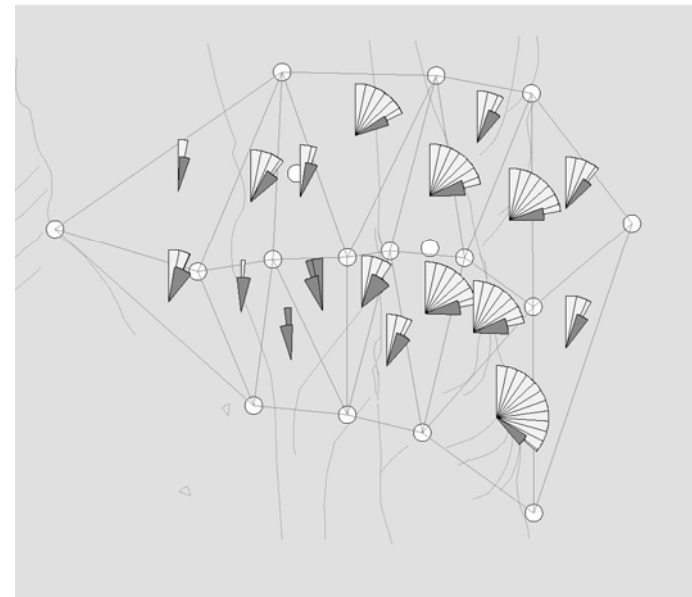
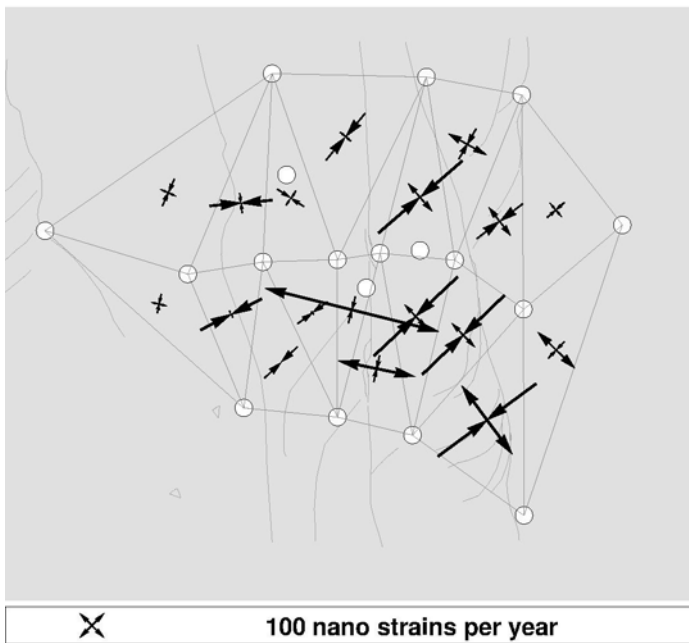
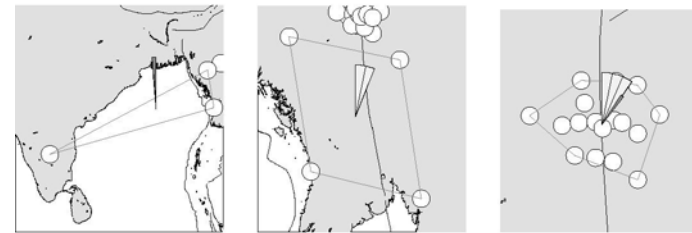
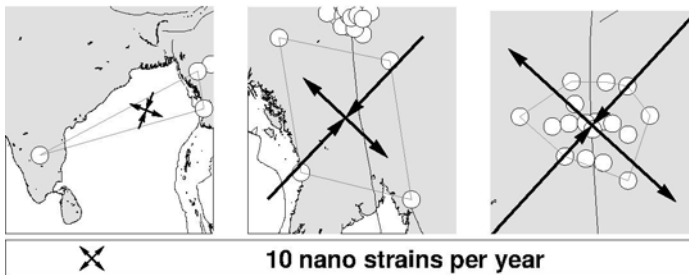
Rotations :

Anti-clockwise/**clockwise**

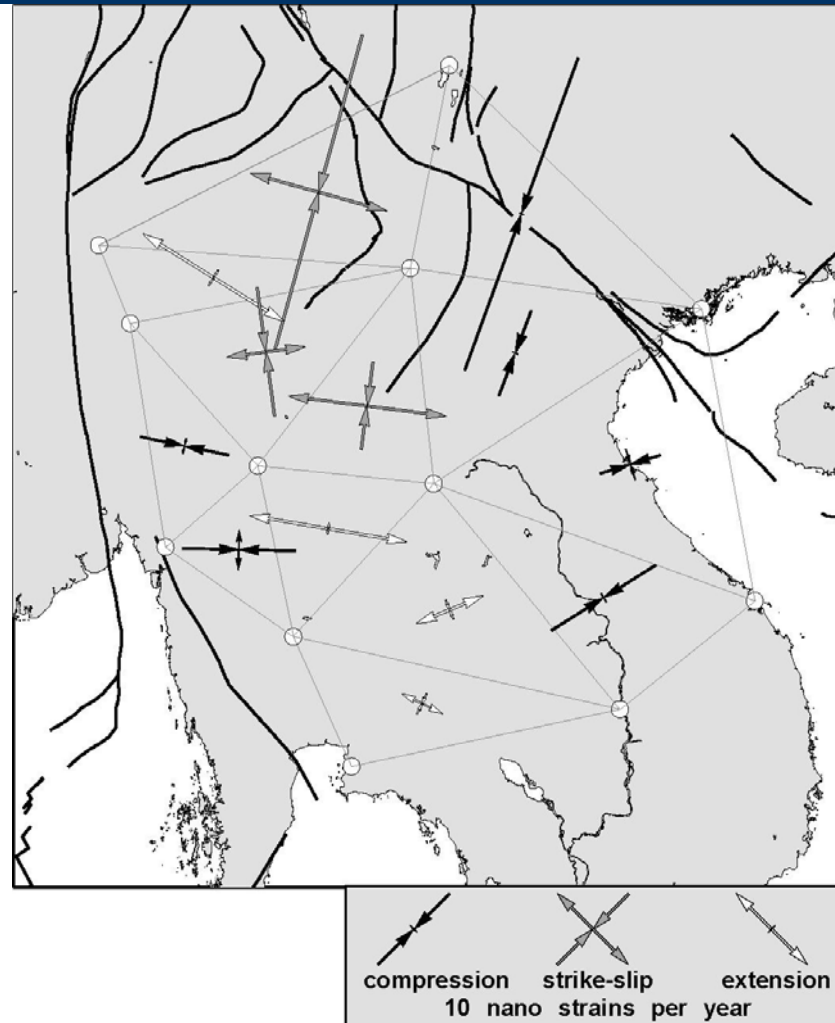
Intensity of strain in GEODYSSSEA network



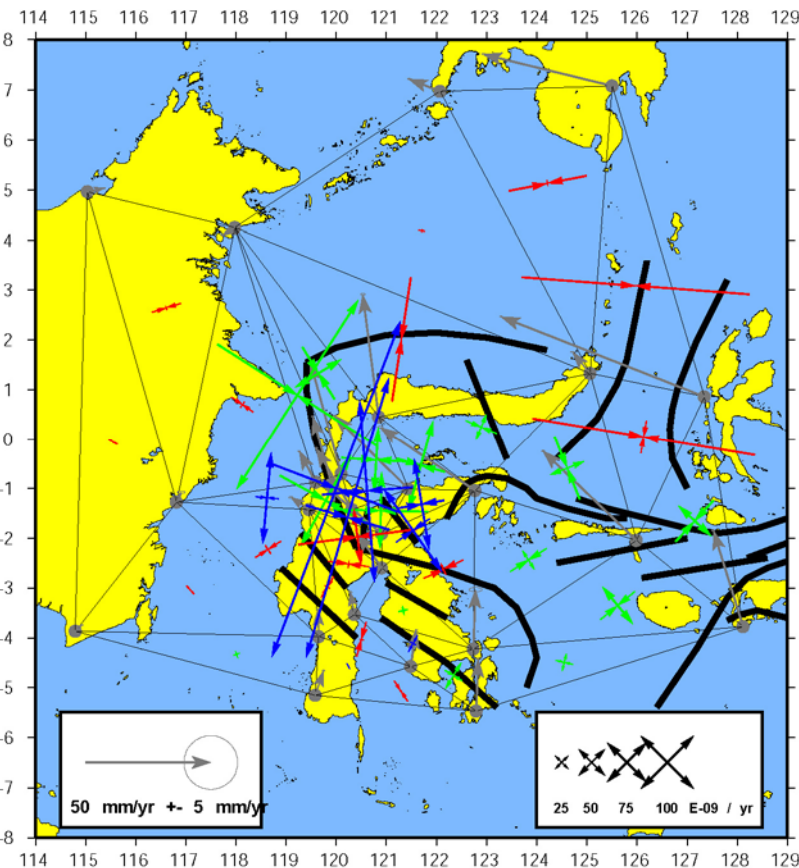
Strain and rotation in Myanmar



Strain in Northern Sundaland (Thailand)

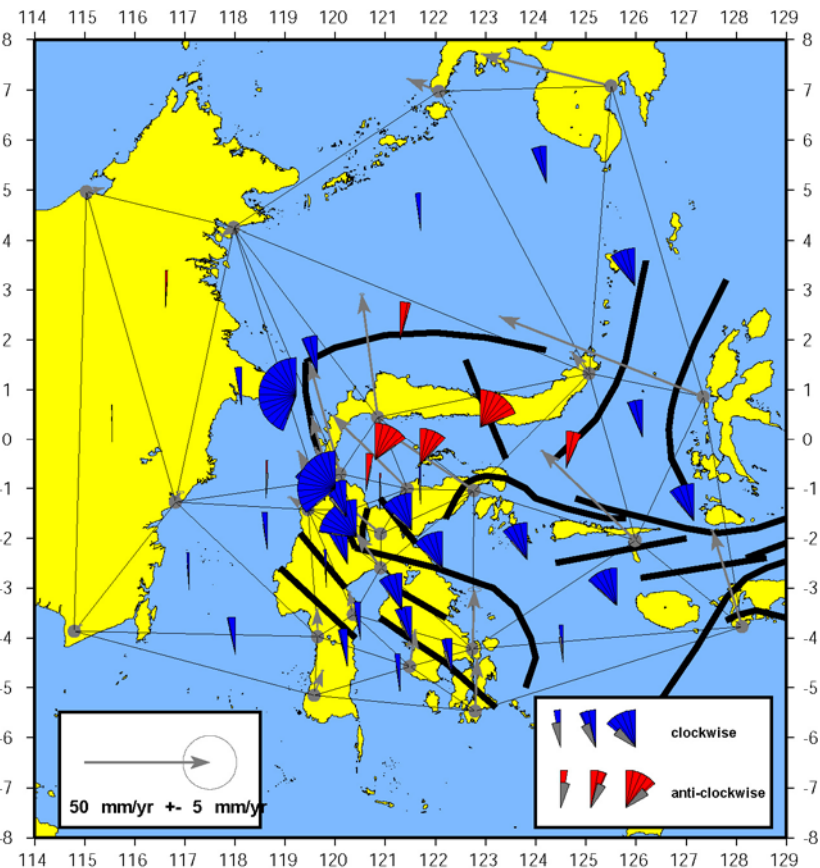


Strain and rotation in Sulawesi network



Strains :

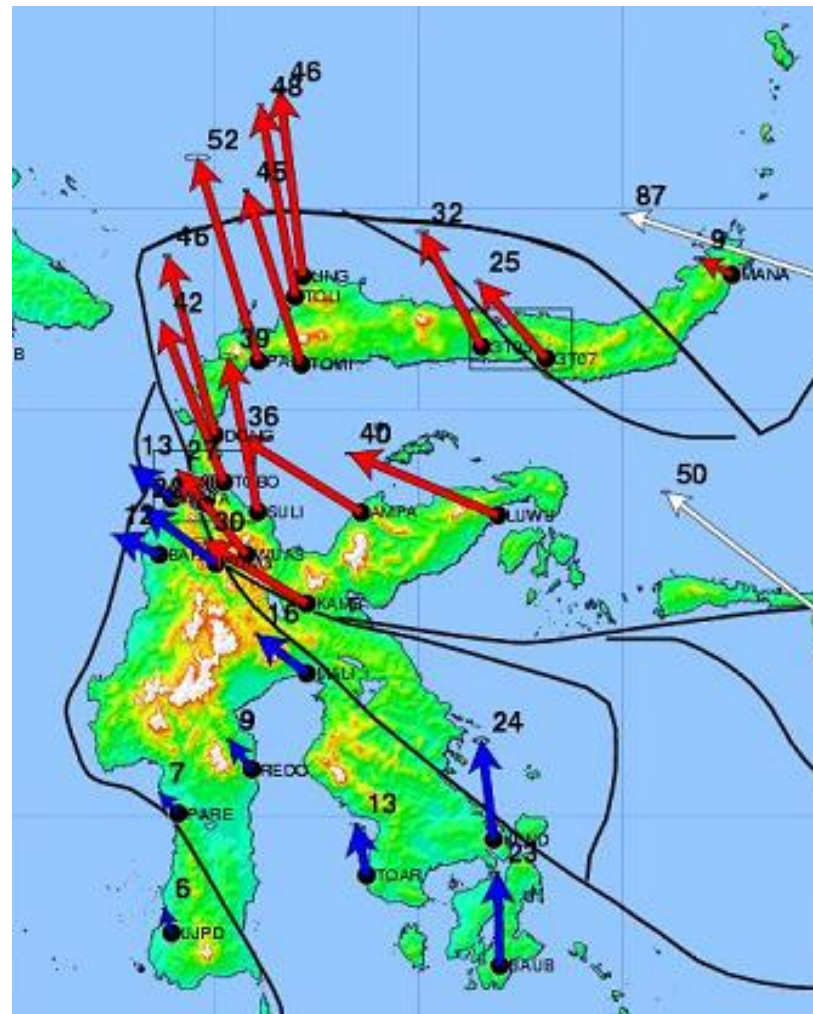
extension/compression/strike-slip



Rotations :

Anti-clockwise/clockwise

Blocks and Internal deformation in Sulawesi



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Blocks and Internal deformation in Sulawesi

