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Three-dimensional elasticity. Elsevier

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W is isotropic iff $W(F) = \varphi(v_1, v_2, v_3)$,
where φ is symmetric with respect to
permutations of the v_i . Proof. Suppose
 W is isotropic. Then $F = RDQ$ for $R, Q \in S$
 $O(3)$ and $D = \text{diag}(v_1, v_2, v_3)$. Hence $W =$
 $W(D)$. But for any permutation P of
 $1, 2, 3$ there exists Q' such that

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$Q \text{diag}(v_1, v_2, v_3) Q^T$
 $= \text{diag}(v_{P1}, v_{P2}, v_{P3})$. The converse
holds since $Q^T F T F Q$ has the

Mathematical Foundations of Elasticity Theory

In mathematics, the elasticity or point
elasticity of a positive differentiable

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function of a positive variable
(positive input, positive output) at point
a is defined as $\epsilon = \frac{\Delta y}{y} \div \frac{\Delta x}{x} = \frac{\Delta y}{y} \cdot \frac{x}{\Delta x} = \frac{\Delta y}{\Delta x} \cdot \frac{x}{y}$
 $\epsilon = \frac{\Delta y}{\Delta x} \cdot \frac{x}{y}$ % % or equivalently $\epsilon = \frac{\Delta y}{\Delta x} \cdot \frac{x}{y}$. It is
thus the ratio of the relative
(percentage) change in the function's
output (y) with respect to the relative
change in its input ...

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Reference is made to Isaac Todhunter, A History of the Theory of Elasticity and of the Strength of Materials Vol. 1 (1886) & Vol. 2 (1893) ed., Karl Pearson. In the analysis of strain I have thought it best to follow Thomson and Tait 's Natural

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Dimensional Elasticity. Part B:
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2 1. Description of Three -
Dimensional Elasticity Figure 1.1.1:

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Let $\varphi: B \subset \mathbb{R}^3 \rightarrow \mathbb{R}^3$ be a sufficiently regular mapping. It is said to be a deformation if (1.1-2) $\det(\mathbf{F}) > 0$ where \mathbf{F} is called the deformation gradient and is a matrix given by

$$\mathbf{F} = \begin{pmatrix} \varphi_{,1}^1 & \varphi_{,2}^1 & \varphi_{,3}^1 \\ \varphi_{,1}^2 & \varphi_{,2}^2 & \varphi_{,3}^2 \\ \varphi_{,1}^3 & \varphi_{,2}^3 & \varphi_{,3}^3 \end{pmatrix}$$

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elasticity, vol 1: three-dimensional
elasticity. North Holland, Amsterdam
zbMATH Google Scholar Fu YB,
Ogden RW (eds) (2001) Nonlinear
elasticity: theory and applications.

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Movchan (1960 a,b) was the first to extend Liapunov's original approach to continuous systems but difficulties encountered for nonlinear elasticity, considered in these lectures, in part

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