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Summary: This volume is a thorough introduction to contemporary research in elasticity, and may be used as a working textbook at the graduate level for courses in pure or applied mathematics or in continuum mechanics. It provides a thorough description (with emphasis on the nonlinear aspects) of the two competing mathematical models of three-dimensional elasticity, together with a mathematical analysis of these models.

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W is isotropic iff W(F) = Φ(v1,v2,v3), where Φ is symmetric with respect to permutations of the vi. Proof. Suppose W is isotropic. Then F = RDQforR,Q∈SO(3)andD=diag(v1,v2,v3). Hence W = W(D). But for any permutation P of 1,2,3 there exists Q ˜ such that Q ˜ diag(v1,v2,v3)Q ˜ T =diag(vP1,vP2,vP3). The converse holds since QTFTFQ has the

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In mathematics, the elasticity or point elasticity of a positive differentiable function f of a positive variable (positive input, positive output) at point a is defined as = ′ ()= → − − = → − () − = → − () − ≈ % % or equivalently = .It is thus the ratio of the relative (percentage) change in the function's output () with respect to the relative change in its input ...

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2 1. Description of Three - Dimensional Elasticity Figure 1.1.1: Let ϕ: BR → R3 be a sufficiently regular mapping. It is said to be a deformation if (1.1-2) det(∇ϕ) >0 where ∇ϕis called the deformation gradient and is a matrix given by ∇ϕ ∂ϕ1 ∂XR1 ∂ϕ1 ∂XR2 ∂ϕ1 ∂XR3 ∂ϕ2 ∂X 1 ∂ϕ2 ∂X R2 ∂ϕ2 ∂X 3 ∂ϕ3 ∂XR1 ∂ϕ3 ∂XR2 ∂ϕ3 ∂XR3

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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 account for the continuing popularity of other methods for investigating stability properties.

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