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W is isotropic

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$\Phi(v_1, v_2, v_3),$

where Φ is symmetric with respect to

permutations of the v_i . Proof.

Suppose W is isotropic. Then $F = RDQ$ for $R, Q \in SO(3)$ and $D = \text{diag}(v_1, v_2, v_3)$. Hence $W = W(D)$. But for any permutation

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If P_1, P_2, P_3 there exists Q^T such that $Q^T \text{diag}(v_1, v_2, v_3) Q = \text{diag}(v_{P1}, v_{P2}, v_{P3})$. The converse holds since $Q^T F T F Q$ has the

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In mathematics,

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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 = '

$(\frac{f'(a)}{f(a)}) = \frac{1}{f(a)} \frac{df}{dx} = \frac{1}{f(a)} \frac{df}{f(a)}$

$(\frac{1}{f(a)}) \frac{df}{f(a)} = \frac{1}{f(a)} \frac{df}{f(a)}$

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equivalently = $\frac{\% \Delta Y}{\% \Delta X}$

. 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 X ...

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Let $\varphi: BR \rightarrow R^3$
be a sufficiently
regular mapping.

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It is said to be a deformation if (1.1-2) $\det(\nabla\phi) > 0$ where $\nabla\phi$ is

called the deformation gradient and is a matrix given by $\nabla\phi = \begin{pmatrix} \partial\phi_1/\partial X_1 & \partial\phi_1/\partial X_2 & \partial\phi_1/\partial X_3 \\ \partial\phi_2/\partial X_1 & \partial\phi_2/\partial X_2 & \partial\phi_2/\partial X_3 \\ \partial\phi_3/\partial X_1 & \partial\phi_3/\partial X_2 & \partial\phi_3/\partial X_3 \end{pmatrix}$

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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

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popularity of
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