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W is isotropic i $W(F) = (v_1, v_2, v_3)$, where 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 P of 1,2,3 there exists $Q \sim$ such that $Q \sim \text{diag}(v_1, v_2, v_3)Q \sim T = \text{diag}(v_{P1}, v_{P2}, v_{P3})$. The converse holds since $QTFQ$ has the

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2 1. Description of Three - Dimensional Elasticity Figure 1.1.1: Let $\chi : B \rightarrow R^3$ be a sufficiently regular mapping. It is said to be a deformation if $(1.1-2) \det(\chi_{i,j}) > 0$ where $\chi_{i,j}$ is called the deformation gradient and is a matrix given by

$$\begin{pmatrix} \chi_{11} & \chi_{12} & \chi_{13} \\ \chi_{21} & \chi_{22} & \chi_{23} \\ \chi_{31} & \chi_{32} & \chi_{33} \end{pmatrix}$$

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Ciarlet PG (1988) Mathematical 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 account for the continuing popularity of other methods for investigating stability properties.

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