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describes the
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fundamental to the
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solutions are $(C y=C x)$

$= 1 2$ and $(C z=C x) = 1$

2 , so that $C = C x(\hat{i} 1 2$

$\hat{j} + 1 2 \hat{k})$.

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Thus, $\mathbf{n} = \frac{\mathbf{e}_1 + \mathbf{e}_2 + \mathbf{e}_3}{\sqrt{3}}$, so
that a unit vector in the
direction of the axis of
rotation is. $\mathbf{n} = \frac{\mathbf{e}_1 + \mathbf{e}_2 + \mathbf{e}_3}{\sqrt{3}}$
 $\mathbf{e}_1 + \mathbf{e}_2 + \mathbf{e}_3$. Lai et al,
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rigid body undergoes a
right hand rotation of
angle θ about an axis
which is in the direction
of the unit vectorm.

CHAPTER 2, PART A

W. Michael Lai is

Professor Emeritus of
Mechanical Engineering
and Orthopaedic

Bioengineering at

Columbia University.

He received his Ph.D in

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in 1962 from the
University of Michigan.

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convenience of
instructors who would

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introduction to modern
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has been fully revised to
serve a dual purpose: for
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and for beginning
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of physical mechanics
that describes the
macroscopic

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This classic text by noted educators, W. Michael Lai, David Rubin and Erhard Krempf, has been used for over 30 years to introduce continuum mechanics from the upper undergraduate to graduate level. It begins with a thorough yet highly accessible grounding in the underlying principles:

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tensor analysis and
kinematics.

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