

Small Oscillations

- Motion near a point of stable equilibrium.

DOF= 1 (one dimension)

- For a system of DOF = 1, with potential $U(q)$:
 - **stable equilibrium** at $U(q)_{\min}$ where $F = -\frac{dU}{dq} = 0$
 - restoring force for small displacements $q - q_0$ is $F = -\frac{dU(q-q_0)}{dq}$
 - **Unstable equilibrium** at $U(q)_{\max}$ where $F = -\frac{dU}{dq} = 0$ as well.
- Consider small deviation from point of stable equilibrium, we use Taylor expansion to show that it is really a small displacement. that is,

$$U(q) \approx U(q_0) + \frac{dU(q_0)}{dq}(q - q_0) + \left(\frac{1}{2}\right) \frac{d^2U(q_0)}{dq^2}(q - q_0)^2 + \dots$$

$$\text{while } \frac{dU(q_0)}{dq}(q - q_0) = 0$$
(1)

letting $x = q - q_0$, we have

$$\begin{cases} U(x) = U(q_0) + \left(\frac{1}{2}\right) \frac{d^2U(q_0)}{dq^2} x^2 \\ \text{also } U(x) = \left(\frac{1}{2}\right) kx^2. \end{cases} \Rightarrow \boxed{k = \frac{d^2U(q_0)}{dq^2} > 0}$$
(2)

we get KE, while choosing $U(q_0) = 0$:

$$T = \frac{1}{2} a(q)^2 \dot{q}^2 = \frac{1}{2} a(q_0 + x) \dot{x}^2 \approx \frac{1}{2} m \dot{x}^2, \text{ letting } m = a(q_0)$$

$$\Rightarrow L = T - U = \frac{1}{2} m \dot{x}^2 - \frac{1}{2} kx^2$$
(3)

EOM for DOF = 1 small Oscillations

using EL on Equation 3, we can get the EOM for one dimensional small Oscillations:

$$m\ddot{x} = -kx$$

$$\Rightarrow \ddot{x} + \omega_0^2 x = 0, \text{ where } \boxed{\omega_0 = \sqrt{\frac{k}{m}} \text{ freq of osc.}}$$
(4)

by magic of ODE, EOM reduces down to:

$$\boxed{x(t) = C_1 \cos(\omega_0 t) + C_2 \sin(\omega_0 t)}, \text{ where } C_1, C_2 \text{ are constants}$$
(5)

by trig magic, this could also be written as

$$x(t) = a \cos(\omega_0 t + \varphi), \text{ where } \begin{cases} a = \sqrt{C_1^2 + C_2^2} & \text{amplitude of oscillation} \\ \omega_0 & \text{frequency of oscillation} \\ \tan \varphi = C_2/C_1 & \text{phase corresponding to origin of time} \end{cases}$$
(6)

energy for 1D small Oscillation

checking $\frac{\partial L}{\partial t} = 0 \Rightarrow$ energy-conservation:

$$\begin{aligned}
 E = T + U &= \frac{1}{2}m\dot{x}^2 + \frac{1}{2}kx^2 \\
 &= \frac{1}{2}ma^2\omega_0^2, [\text{constant}]
 \end{aligned}
 \tag{7}$$

Damped 1D oscillation, and Complex representation

[I dont like the how the subscripts are used in this lecture but I guess this is what we are stuck with.]

- when there is damping (friction, resistance, etc) $F_{\text{fric}} = -\beta\dot{x}$, the EOM becomes:

$$\begin{aligned}
 \ddot{x} + 2\gamma\dot{x} + \omega_0^2x &= 0, \\
 \text{where } 2\gamma &= \frac{\beta}{m}, \omega_0 = \sqrt{\frac{k}{m}}
 \end{aligned}
 \tag{8}$$

with ansatz $x(t) = e^{rt}$, $\dot{x} = re^{rt}$, $\ddot{x} = r^2e^{rt}$, the solution to Equation 8 is:

$$\begin{aligned}
 r^2 + 2\gamma r + \omega_0^2 &= 0, \\
 \text{which has solution } r_+, r_- &= -\gamma \pm \sqrt{\gamma^2 - \omega_0^2} \\
 \Rightarrow x(t) &= C_1e^{r_+t} + C_2e^{r_-t},
 \end{aligned}
 \tag{9}$$

notice the r subscripts here: r_+, r_-

underdamped, overdamped, and critically damped

Recall from your ODE class...

Equation 9 has the following 3 cases, each with different physical interpretation:

1. underdamped:

$$\gamma < \omega_0 \Rightarrow 2 \text{ complex roots: } \begin{cases} r_{\pm} = -\gamma \pm i\sqrt{\omega_0^2 - \gamma^2} = -\gamma \pm i\omega \\ \omega = \sqrt{\omega_0^2 - \gamma^2} \end{cases}
 \tag{10}$$

The EOM is thus a linear combination of two complex exponentials:

$$\begin{aligned}
 x(t) &= e^{-\gamma t}(C_1e^{i\omega t} + C_2e^{-i\omega t}) \\
 &= e^{-\gamma t}(A \cos(\omega t) + B \sin(\omega t)) \\
 &= ae^{-\gamma t} \cos(\omega t + \alpha)
 \end{aligned}$$

$$\text{-- said Euler, where } \begin{cases} A = C_1 + C_2 \\ B = i(C_1 - C_2) \end{cases}
 \tag{11}$$

a, α are constants

The solution is a damped oscillation with frequency ω , and amplitude exponentially decaying with time