



## 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:

$$\boxed{x(t) = C_1 \cos(\omega_0 t) + C_2 \sin(\omega_0 t)}$$

where  $C_1, C_2$  are constants

(5)

by trig magic, this could also be written as

$$x(t) = a \cos(\omega_0 t + \varphi),$$

$$\text{where } \begin{cases} a = \sqrt{C_1^2 + C_2^2} & \text{amplitude of oscillation} \\ \omega_0 & \text{frequency of oscillation} \\ \tan \varphi = C_2/C_1 & \text{phase at } t=0 \end{cases}$$
(6)

### energy for 1D small Oscillation

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

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

### 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:

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

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

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

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:

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

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

$$\begin{aligned} x(t) &= e^{-\gamma t}(C_1e^{i\omega t} + C_2e^{-i\omega t}) \\ &= e^{-\gamma t}(A \cos(\omega t) + B \sin(\omega t)) \\ \text{-- said Euler, where } &\begin{cases} A = C_1 + C_2 \\ B = i(C_1 - C_2) \end{cases} \\ &= ae^{-\gamma t} \cos(\omega t + \alpha) \\ a, \alpha &\text{ are constants} \end{aligned} \quad (11)$$

The solution is a damped oscillation with frequency  $\omega$ , and amplitude exponentially decaying with time.