

Meccanica classica

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Indice

$$(q_1, \dots, q_d) \rightarrow (\tilde{q}_1, \dots, \tilde{q}_d)$$

$$\begin{cases} q_j = q_j(\tilde{q}_1, \dots, \tilde{q}_d) \rightarrow \dot{q}_j = \dot{q}_j(\underline{\tilde{q}}, \underline{\dot{\tilde{q}}}) & J_{kj} = \frac{\delta q_k}{\delta \tilde{q}_j} \quad \det J \neq 0 \\ j = 1, \dots, d \end{cases}$$

$$\begin{cases} \tilde{q}_j(q_1, \dots, q_d) \\ j = 1, \dots, d \end{cases}$$

$$\mathcal{L}(q_1, \dots, q_d, \dot{q}_1, \dots, \dot{q}_d) \quad \tilde{\mathcal{L}}(\underline{\tilde{q}}, \underline{\dot{\tilde{q}}}) = \mathcal{L}(q(\underline{\tilde{q}}), \dot{q}(\underline{\tilde{q}}, \underline{\dot{\tilde{q}}}))$$

Prop. $q(t)$ è soluzione E-L per $\mathcal{L}(q, \dot{q}) \iff \tilde{q}(t)$ è soluzione per $\mathcal{L}(\tilde{q}, \dot{\tilde{q}})$

Dimostrazione. $(\Rightarrow) q(t)$ è soluzione E-L per \mathcal{L}

$$\begin{aligned} \frac{d}{dt} \frac{\delta \tilde{\mathcal{L}}}{\delta \dot{\tilde{q}}_j} &= \frac{d}{dt} \left(\sum_{i=1}^d \frac{\delta \mathcal{L}}{\delta \dot{q}_i} \frac{\delta \dot{q}_i}{\delta \dot{\tilde{q}}_j} \right) = \frac{d}{dt} \left(\sum_{i=1}^d \frac{\delta \mathcal{L}}{\delta \dot{q}_i} \underbrace{\frac{\delta \dot{q}_i}{\delta \dot{\tilde{q}}_j}}_{\text{lemma1}} \right) = \sum_{i=1}^d \left[\left(\frac{d}{dt} \frac{\delta \mathcal{L}}{\delta \dot{q}_i} \right) \frac{\delta \dot{q}_i}{\delta \dot{\tilde{q}}_j} + \frac{\delta \mathcal{L}}{\delta \dot{q}_i} \underbrace{\frac{d}{dt} \frac{\delta \dot{q}_i}{\delta \dot{\tilde{q}}_j}}_{\text{lemma2}} \right] = \\ &= \sum_{i=1}^d \left[\left(\frac{d}{dt} \frac{\delta \mathcal{L}}{\delta \dot{q}_i} \right) \frac{\delta \dot{q}_i}{\delta \dot{\tilde{q}}_j} + \frac{\delta \mathcal{L}}{\delta \dot{q}_i} \frac{\delta \dot{q}_i}{\delta \dot{\tilde{q}}_j} \right] \end{aligned}$$

Uso ipotesi

$$= \sum_{i=1}^d \left(\frac{\delta \mathcal{L}}{\delta \dot{q}_i} \frac{\delta \dot{q}_i}{\delta \dot{\tilde{q}}_j} + \frac{\delta \mathcal{L}}{\delta \dot{q}_i} \frac{\delta \dot{q}_i}{\delta \dot{\tilde{q}}_j} \right) = \frac{\delta \tilde{\mathcal{L}}}{\delta \dot{\tilde{q}}_j}$$

□

Prop. \forall scelta di $F(q, t)$ e $\alpha \neq 0 \in \mathbb{R}$ allora

$$\mathcal{L}(q, \dot{q}, t) \quad \mathcal{L}'(q, \dot{q}, t) = \alpha(q, \dot{q}, t) + \frac{dF}{dt}$$

conducono alla stessa soluzione per E-L

Dimostrazione.

$$L_0 = \frac{dF}{dt} = \dot{F} \quad \mathcal{L}' = \alpha \mathcal{L} + L_0$$

$$\frac{d}{dt} \frac{\delta \mathcal{L}'}{\delta \dot{q}_j} = \alpha \frac{d}{dt} \frac{\delta \mathcal{L}}{\delta \dot{q}_j} + \frac{d}{dt} \frac{\delta L_0}{\delta \dot{q}_j}$$

$$\frac{d}{dt} \frac{\delta L_0}{\delta \dot{q}_j} = \frac{d}{dt} \frac{\delta \dot{F}}{\delta \dot{q}_j} \underbrace{=}_{\text{Lemma1}} \frac{d}{dt} \frac{\delta F}{\delta \dot{q}_j} \underbrace{=}_{\text{Lemma2}} \frac{\delta \dot{F}}{\delta \dot{q}_j} = \alpha \frac{d}{dt} \frac{\delta \mathcal{L}}{\delta \dot{q}_j} + \frac{\delta L_0}{\delta \dot{q}_j}$$

□