

Tensor Calculus
J.L. Synge and A.Schild (Dover Publication)
Solutions to exercises
Part II
Chapters V to VIII

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Applications to Classical Mechanics

5.1 p153 - Exercise

If μ^α are the contra-variant components of a unit vector in a surface S , show that $\mu^\alpha f_\alpha$ is the physical component of acceleration in the direction tangent to S defined by μ^α .

As we are in an Euclidean space we can interpret $a_{mn}\mu^\alpha f^\alpha$ as $|\mu||f|\cos\theta$ with θ the angle between the two vectors. As $|\mu| = 1$ we have

$$a_{mn}\mu^\alpha f^\alpha = \mu^\alpha f_\alpha \quad (1)$$

$$= |f|\cos\theta \quad (2)$$

which is the projection of the vector f on the unit vector μ .



5.2 p154 - Clarification to 5.226.

$$5.226. \quad \mathbf{v} \frac{d\mathbf{v}}{ds} = \mathbf{0}, \quad \bar{\kappa} \mathbf{v}^2 = \mathbf{0}$$

Assuming that the particle is not at rest $v \neq 0$, and therefore $\bar{\kappa} = 0$. ***Since this implies that the curve is a geodesic...***

The assertion in bold is a direct consequence

$$2.513. \quad \frac{\delta \frac{dx^r}{ds}}{\delta s} = 0$$

As in **5.233** we have $\frac{\delta \lambda^\alpha}{\delta s} = \frac{\delta \frac{dx^\alpha}{ds}}{\delta s} = 0$, the considered curve follows the geodesic curve.



5.3 p155 - Exercise

Show that in relativity the force 4-vector X^r lies along the first normal of the trajectory in space-time. Express the first curvature in terms of the proper mass m of the particle and the magnitude X of X^r .

Let us recall the first Frenet formula **2.705** without forgetting that the metric form is not positive-definite,

$$\frac{\delta \lambda^r}{\delta s} = \kappa \nu^r, \quad \epsilon_{(1)} \nu_n \nu^n = 1$$

As **5.299**

$$m \frac{\delta \lambda^r}{\delta s} = X^r$$

it is clear that $X^r = m \kappa \nu^r$ and is collinear with the first normal.

$$X^r = m \kappa \nu^r \tag{1}$$

$$\times \quad a_{mr} X^m \quad \Rightarrow \quad \underbrace{a_{mr} X^m X^r}_{=(X^1)^2 + (X^2)^2 + (X^3)^2 - (X^4)^2} = m \kappa \underbrace{a_{mr} \nu^m \nu^r}_{=\epsilon_{(1)}} \tag{2}$$

$$\Rightarrow \quad \kappa = \epsilon_{(1)} \frac{(X^1)^2 + (X^2)^2 + (X^3)^2 - (X^4)^2}{m}$$



5.4 p156 - Clarification to 5.231

Interpretation of

5.231.

$$M_{rs} = \epsilon_{rsn} M_n = z_r F_s - z_s F_r$$

What do the M_{rs} represent?

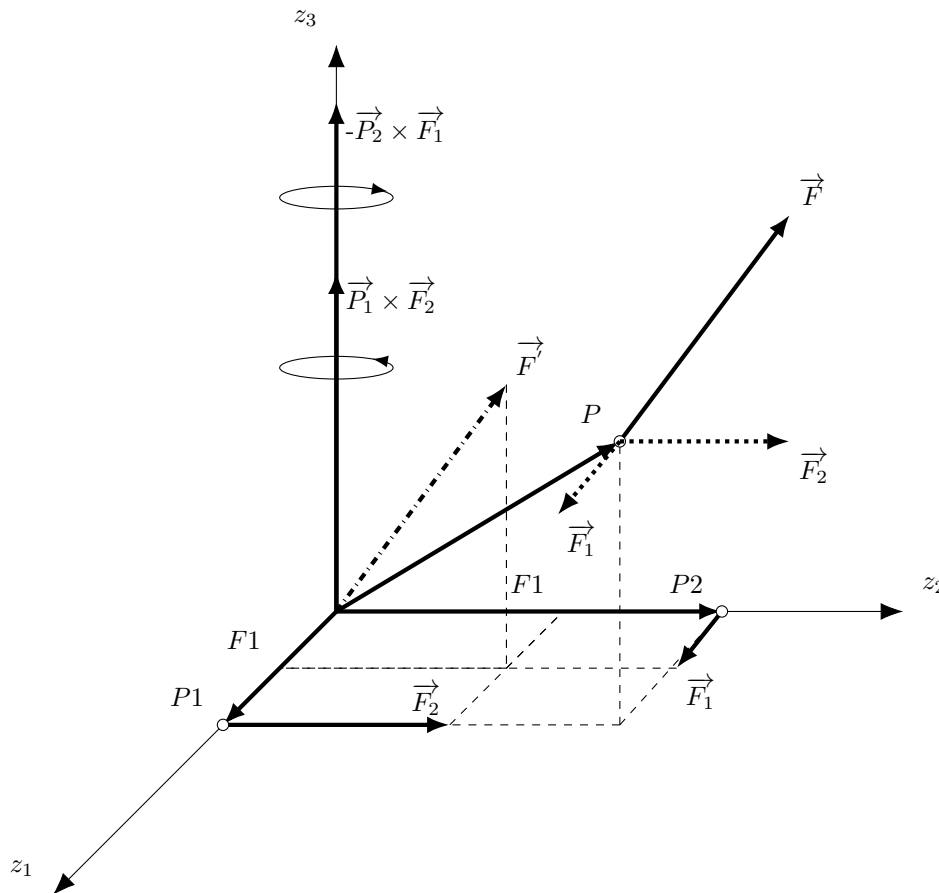


Figure 5.1: Interpretation of the tensor moment M_{12}

Let's consider a mass point P on which a force \vec{F} is acting. The force has components (F_x, F_y, F_z) in the space V_3' (which is by the way not the space V_3 of the considered mass point).

Let's investigate the element M_{12} of the *tensor moment*.

$P_1 F_2 \vec{e}_3$ is the vector product $\vec{P}_1 \times \vec{F}_2$ and is as such the torque of the component F_2 of \vec{F} acting on the mass point situated at P_1 . The origin being fixed, \vec{F}_2 tries to move P_1 , clockwise along the z_3 axis. The same is true for the component \vec{F}_1 acting on the mass point situated at P_2 , and is represented here by the vector $-\vec{P}_2 \times \vec{F}_1$ (\vec{F}_1 tries to move P_2 , counter clockwise along the z_3 axis). Hence, $P_1 F_2 - P_2 F_1$ is the net force trying to move the point P along the z_3 axis (i.e. in the plane \parallel with the $z_3 = 0$ plane).



5.5 p156 - Clarification to 5.234

$$\mathbf{5.234.} \quad \frac{dh_r}{dt} = M_r$$

$$h_r = m\epsilon_{rmn}z_mv_n \tag{1}$$

$$\Rightarrow \quad \frac{dh_r}{dt} = m\epsilon_{rmn} \frac{dz_m}{dt} v_n + m\epsilon_{rmn} z_m \frac{dv_n}{dt} \tag{2}$$

$$= m \underbrace{\epsilon_{rmn} v_m v_n}_{=0} + \underbrace{\epsilon_{rmn} z_m F_n}_{=M_r} \tag{3}$$

$$= M_r \tag{4}$$



5.6 p158-159 - Clarification to 5.313

$$\mathbf{5.313.} \quad \omega_{rs} = -\omega_{sr}$$

From 5.310 and the vector character of v_r and z_r (for transformations which do not change the origin), **it follows that ω_{rs} is a Cartesian tensor of second order.**

Be

$$v_r = -\omega_{rn} z_n \quad (1)$$

Considering orthogonal transformation in a flat space $z'_m = A_{mr} z_r + B_m$ with $B_m = 0$ as we consider only transformations which do not change the origin. Differentiation with the parameter t gives

$$v'_m = A_{mr} v_r \quad (2)$$

$$= -\omega_{rn} A_{mr} z_n \quad (3)$$

$$(4)$$

But $z'_q = A_{qr} z_r \Rightarrow A_{qn} z'_q = A_{qn} A_{qr} z_r \Rightarrow A_{qn} z'_q = z_n$ Hence

$$v'_m = -\omega_{rn} A_{mr} z_n \quad (5)$$

$$= -\underbrace{\omega_{rn} A_{mr} A_{qn}}_{\stackrel{\text{def}}{=} \omega'_{mq}} z'_q \quad (6)$$

$$v'_m = -\omega'_{mq} z'_q \quad (7)$$



5.7 p159 - Exercise

Show that if a rigid body rotates about the point $z_r = b_r$ as fixed point, the velocity of a general point of the body is given by

$$v_r = -\omega_{rm} (z_m - b_m)$$

By **5.302.**:

$$\left(z_m^{(1)} - z_m^{(2)}\right) \left(dz_m^{(1)} - dz_m^{(2)}\right) = 0 \quad (1)$$

At the fixed point we have $z_m^{(2)} = b_m$ and $dz_m^{(2)} = 0$, hence

$$\left(z_m^{(1)} - b_m\right) \left(dz_m^{(1)}\right) = 0 \quad (2)$$

$$\Rightarrow z_m^{(1)} dz_m^{(1)} = b_m dz_m^{(1)} \quad (3)$$

As this is true for any point of the rigid mass, expanding (1) and using (3) we get when dividing by dt

$$\left(z_m^{(2)} - b_m\right) v_m^{(1)} + \left(z_m^{(1)} - b_m\right) v_m^{(2)} = 0 \quad (4)$$

Taking twice the partial derivative $\frac{\partial^2}{\partial z_p^{(1)} \partial z_q^{(1)}}$ we get

$$\left(z_m^{(2)} - b_m\right) \frac{\partial^2 v_m}{\partial z_p^{(1)} \partial z_q^{(1)}} = 0 \quad (5)$$

As this is true for any arbitrary point in the rigid body we get

$$\frac{\partial^2 v_m}{\partial z_p^{(1)} \partial z_q^{(1)}} = 0 \quad (6)$$

$$\Rightarrow v_m = K_{mr} z_r + B_m \quad (7)$$

At the fixed point we have

$$K_{mr} b_r + B_m = 0 \quad (8)$$

Plugging this in (7)

$$v_m = K_{mr} (z_r - b_m) \quad (9)$$

Putting $K_{mr} = -\omega_{mr}$ gives us indeed the asked expression.



5.8 p161 - Clarification to 5.325 and 5.326

$$\mathbf{5.325.} \quad \Omega_{np} \sum (m f_n z_p) = \Omega_{np} \sum F_n z_p$$

and hence, since Ω_{np} is arbitrary,

$$\mathbf{5.326.} \quad \sum m (f_n z_p - f_p z_n) = \sum (F_n z_p - F_p z_n)$$

To be complete the following step should be inserted

$$\Omega_{np} \sum (m f_n z_p) = \Omega_{np} \sum F_n z_p \quad (1)$$

$$\text{As } \Omega_{np} \text{ is skew-symmetric:} \quad -\Omega_{np} \sum (m f_p z_n) = -\Omega_{np} \sum F_p z_n \quad (2)$$

$$(1)+(2) \quad \Omega_{np} \sum m (f_n z_p - f_p z_n) = \Omega_{np} \sum (F_n z_p - F_p z_n) \quad (3)$$

and hence, since Ω_{np} is arbitrary,

$$\mathbf{5.326.} \quad \sum m (f_n z_p - f_p z_n) = \sum (F_n z_p - F_p z_n)$$



5.9 p161 - Clarification to 5.329 and 5.330

$$\begin{aligned} \text{5.329.} \quad h_{np} &= \sum m (\omega_{nq} z_q z_p - \omega_{pq} z_q z_n) \\ &= J_{npqr} \omega_{rq} \end{aligned}$$

where

$$\text{5.330.} \quad J_{npqr} = \sum m (\delta_{nr} z_q z_p - \delta_{pr} z_n z_q)$$

$$h_{np} = \sum m (\omega_{nq} z_q z_p - \omega_{pq} z_q z_n) \quad (1)$$

$$= \sum m (\omega_{rq} \delta_{rn} z_q z_p - \omega_{rq} \delta_{rp} z_q z_n) \quad (2)$$

$$= \omega_{rq} \sum m (\delta_{rn} z_q z_p - \delta_{rp} z_q z_n) \quad (3)$$

$$= J_{npqr} \omega_{rq} \quad (4)$$



5.10 p166 - Exercise

Deduce immediately from **5.420.** that the Coriolis force is perpendicular to the velocity.

$$G'_s = 2m\omega'_{sm}(S', S)v'_m(S') \quad (1)$$

$$\times v'_s(S') \quad : \quad G'_s v'_s(S') = m \left(\omega'_{sm}(S', S)v'_m(S')v'_s(S') + \omega'_{ms}(S', S)v'_m(S')v'_s(S') \right) \quad (2)$$

$$= 0 \quad \text{as } \omega'_{ms} \text{ is skew-symmetric} \quad (3)$$



5.11 p166 - Exercise

Show that if $N = 3$ and $\dot{\omega}'_r(S', S) = 0$, then the centrifugal force may be written

$$\mathbf{5.422.} \quad C'_s = m\omega'_n(S', S)\omega'_n(S', S)z'_s - m\omega'_n(S', S)z'_n\omega'_s(S', S)$$

Deduce that C'_s is coplanar with the vectors $\omega'_s(S', S)$ and z'_n and perpendicular to the former.

By **5.420.** with $\dot{\omega}'_r(S', S) = 0$ and using **5.316.** ($\omega'_{rs} = \epsilon_{rsn}\omega'_n$)

$$C'_s = m\omega'_{sm}(S', S)\omega'_{nm}(S', S)z'_n \quad (1)$$

$$= m\epsilon_{smk}\omega'_k(S', S)\epsilon_{nmp}\omega'_p(S', S)z'_n \quad (2)$$

$$= m\epsilon_{msk}\epsilon_{mnp}\omega'_k(S', S)\omega'_p(S', S)z'_n \quad (3)$$

$$= m(\delta_{sn}\delta_{kp} - \delta_{sp}\delta_{kn})\omega'_k(S', S)\omega'_p(S', S)z'_n \quad (4)$$

$$= m\delta_{sn}\delta_{kp}\omega'_k(S', S)\omega'_p(S', S)z'_n - m\delta_{sp}\delta_{kn}\omega'_k(S', S)\omega'_p(S', S)z'_n \quad (5)$$

$$= m\omega'_p(S', S)\omega'_p(S', S)z'_s - m\omega'_n(S', S)\omega'_s(S', S)z'_n \quad (6)$$

To deduce that C'_s is coplanar with the vectors $\omega'_s(S', S)$ and z'_n we calculate the mixed triple product

$$P = \epsilon_{spr}C'_s\omega'_p(S', S)z'_r \quad (7)$$

$$= m \underbrace{\epsilon_{spr}\omega'_n(S', S)\omega'_n(S', S)z'_s\omega'_p(S', S)z'_r}_{=0} - \underbrace{m\epsilon_{spr}\omega'_n(S', S)\omega'_s(S', S)z'_n\omega'_p(S', S)z'_r}_{=0} \quad (8)$$

$$= 0 \quad (9)$$

Both terms vanish: the first by the presence of the terms $\epsilon_{spr}z'_s z'_r$ which cancel each other and for the second by the terms $\epsilon_{spr}\omega'_s(S', S)\omega'_p(S', S)$. As $P = 0$, the three vectors are coplanar.

We now calculate the inner product $C'_s\omega'_s(S', S)$

$$P = m\omega'_n(S', S)\omega'_n(S', S)z'_s\omega'_s(S', S) - \underbrace{m\omega'_n(S', S)\omega'_s(S', S)z'_n\omega'_s(S', S)}_{\Leftrightarrow m\omega'_n(S', S)\omega'_n(S', S)z'_s\omega'_s(S', S)} \quad (10)$$

$$= 0 \quad (11)$$



5.12 p168 - Exercise

Taking $N = 3$, show that **5.424** may be reduced to the usual Euler equations:

$$I_{11} \frac{d\omega'_1(S', S)}{dt} - (I_{22} - I_{33}) \omega_2(S', S) \omega'_3(S', S) = M'_1$$

and two similar equations.

We first begin with an approach which leads to nothing. I probably made a reasoning error. I give here the whole calculation as this was interesting and also to, later, find my mistake. After this buggy solution, I will give a second version, which works.

5.424:

$$M'_{ab} = J'_{abrq} \frac{d\omega'_{rq}(S', S)}{dt} + J'_{cdrq} (\delta_{ac} \delta_{du} \delta_{bv} + \delta_{bd} \delta_{cu} \delta_{av}) \omega'_{rq}(S', S) \omega'_{uv}(S', S) = \quad (1)$$

$$\times \epsilon_{sab}: \quad 2M'_s = \epsilon_{sab} J'_{abrq} \frac{d\omega'_{rq}(S', S)}{dt} + \epsilon_{sab} J'_{cdrq} (\delta_{ac} \delta_{du} \delta_{bv} + \delta_{bd} \delta_{cu} \delta_{av}) \omega'_{rq}(S', S) \omega'_{uv}(S', S) \quad (2)$$

Using $\omega'_{rq}(S', S) = \epsilon_{rqt} \omega'_t(S', S)$ and $I_{st} = \frac{1}{2} J'_{abrq} \epsilon_{abs} \epsilon_{rqt}$

$$2M'_s = 2I_{st} \frac{d\omega'_t(S', S)}{dt} + \epsilon_{sab} \epsilon_{rqi} \epsilon_{uvj} J'_{cdrq} (\delta_{ac} \delta_{du} \delta_{bv} + \delta_{bd} \delta_{cu} \delta_{av}) \omega'_i(S', S) \omega'_j(S', S) \quad (3)$$

$$= \begin{cases} 2I_{st} \frac{d\omega'_t(S', S)}{dt} \\ + \left(\epsilon_{sab} \epsilon_{rqi} \epsilon_{uvj} J'_{cdrq} \delta_{ac} \delta_{du} \delta_{bv} + \epsilon_{sab} \epsilon_{rqi} \epsilon_{uvj} J'_{cdrq} \delta_{bd} \delta_{cu} \delta_{av} \right) \omega'_i(S', S) \omega'_j(S', S) \end{cases} \quad (4)$$

$$= \begin{cases} 2I_{st} \frac{d\omega'_t(S', S)}{dt} \\ + \left(\epsilon_{scb} \epsilon_{rqi} \epsilon_{dbj} J'_{cdrq} + \epsilon_{sad} \epsilon_{rqi} \epsilon_{caj} J'_{cdrq} \right) \omega'_i(S', S) \omega'_j(S', S) \end{cases} \quad (5)$$

$$= \begin{cases} 2I_{st} \frac{d\omega'_t(S', S)}{dt} \\ + (\epsilon_{bcs} \epsilon_{bdj}) \epsilon_{rqi} J'_{cdrq} \omega'_i(S', S) \omega'_j(S', S) \\ + (\epsilon_{asd} \epsilon_{acj}) \epsilon_{rqi} J'_{cdrq} \omega'_i(S', S) \omega'_j(S', S) \end{cases} \quad (6)$$

$$= \begin{cases} 2I_{st} \frac{d\omega'_t(S', S)}{dt} \\ + (\delta_{cd} \delta_{sj} - \delta_{cj} \delta_{sd}) \epsilon_{rqi} J'_{cdrq} \omega'_i(S', S) \omega'_j(S', S) \\ + (\delta_{sc} \delta_{dj} - \delta_{sj} \delta_{dc}) \epsilon_{rqi} J'_{cdrq} \omega'_i(S', S) \omega'_j(S', S) \end{cases} \quad (7)$$

$$= \begin{cases} 2I_{st} \frac{d\omega'_t(S', S)}{dt} \\ +\epsilon_{rqi} J'_{ccrq} \omega'_i(S', S) \omega'_s(S', S) \\ -\epsilon_{rqi} J'_{jsrq} \omega'_i(S', S) \omega'_j(S', S) \\ +\epsilon_{rqi} J'_{sjrq} \omega'_i(S', S) \omega'_j(S', S) \\ -\epsilon_{rqi} J'_{ccrq} \omega'_i(S', S) \omega'_s(S', S) \end{cases} \quad (8)$$

giving

$$2M'_s = \begin{cases} 2I_{st} \frac{d\omega'_t(S', S)}{dt} \\ +\epsilon_{rqi} J'_{sjrq} \omega'_i(S', S) \omega'_j(S', S) \\ -\epsilon_{rqi} J'_{jsrq} \omega'_i(S', S) \omega'_j(S', S) \end{cases} \quad (9)$$

For $s = 1$:

	$+\epsilon_{rqi} J_{1jrq} \omega_i \omega_j$	$-\epsilon_{rqi} J_{j1rq} \omega_i \omega_j$
ϵ_{123}	$+J_{1112} \omega_3 \omega_1 + J_{1212} \omega_3 \omega_2 + J_{1312} \omega_3 \omega_3$	$-J_{1112} \omega_3 \omega_1 - J_{2112} \omega_3 \omega_2 - J_{3112} \omega_3 \omega_3$
ϵ_{132}	$-J_{1113} \omega_2 \omega_1 - J_{1213} \omega_2 \omega_2 - J_{1313} \omega_2 \omega_3$	$+J_{1113} \omega_2 \omega_1 + J_{2113} \omega_2 \omega_2 + J_{3113} \omega_2 \omega_3$
ϵ_{213}	$-J_{1121} \omega_3 \omega_1 - J_{1221} \omega_3 \omega_2 - J_{1321} \omega_3 \omega_3$	$+J_{1121} \omega_3 \omega_1 + J_{2121} \omega_3 \omega_2 + J_{3121} \omega_3 \omega_3$
ϵ_{231}	$+J_{1123} \omega_1 \omega_1 + J_{1223} \omega_1 \omega_2 + J_{1323} \omega_1 \omega_3$	$-J_{1123} \omega_1 \omega_1 - J_{2123} \omega_1 \omega_2 - J_{3123} \omega_1 \omega_3$
ϵ_{321}	$-J_{1132} \omega_1 \omega_1 - J_{1232} \omega_1 \omega_2 - J_{1332} \omega_1 \omega_3$	$+J_{1132} \omega_1 \omega_1 + J_{2132} \omega_1 \omega_2 + J_{3132} \omega_1 \omega_3$
ϵ_{312}	$+J_{1131} \omega_2 \omega_1 + J_{1231} \omega_2 \omega_2 + J_{1331} \omega_2 \omega_3$	$-J_{1131} \omega_2 \omega_1 - J_{2131} \omega_2 \omega_2 - J_{3131} \omega_2 \omega_3$

Taking into account that $J_{abcd} = 0$ for $a \neq c \wedge b \neq d$

	$+\epsilon_{rqi} J_{1jrq} \omega_i \omega_j$	$-\epsilon_{rqi} J_{j1rq} \omega_i \omega_j$
ϵ_{123}	$+J_{1112} \omega_3 \omega_1 + J_{1212} \omega_3 \omega_2 + J_{1312} \omega_3 \omega_3$	$-J_{1112} \omega_3 \omega_1$
ϵ_{132}	$-J_{1113} \omega_2 \omega_1 - J_{1213} \omega_2 \omega_2 - J_{1313} \omega_2 \omega_3$	$+J_{1113} \omega_2 \omega_1$
ϵ_{213}	$-J_{1121} \omega_3 \omega_1$	$+J_{1121} \omega_3 \omega_1 + J_{2121} \omega_3 \omega_2 + J_{3121} \omega_3 \omega_3$
ϵ_{231}	$+J_{1323} \omega_1 \omega_3$	$-J_{2123} \omega_1 \omega_2$
ϵ_{321}	$-J_{1232} \omega_1 \omega_2$	$+J_{3132} \omega_1 \omega_3$
ϵ_{312}	$+J_{1131} \omega_2 \omega_1$	$-J_{1131} \omega_2 \omega_1 - J_{2131} \omega_2 \omega_2 - J_{3131} \omega_2 \omega_3$

Opposite sign terms vanish, giving

	$+\epsilon_{rqi}J_{1jrq}\omega_i\omega_j$	$-\epsilon_{rqi}J_{j1rq}\omega_i\omega_j$
ϵ_{123}	$+J_{1212}\omega_3\omega_2 + J_{1312}\omega_3\omega_3$	
ϵ_{132}	$-J_{1213}\omega_2\omega_2 - J_{1313}\omega_2\omega_3$	
ϵ_{213}		$+J_{2121}\omega_3\omega_2 + J_{3121}\omega_3\omega_3$
ϵ_{231}	$+J_{1323}\omega_1\omega_3$	$-J_{2123}\omega_1\omega_2$
ϵ_{321}	$-J_{1232}\omega_1\omega_2$	$+J_{3132}\omega_1\omega_3$
ϵ_{312}		$-J_{2131}\omega_2\omega_2 - J_{3131}\omega_2\omega_3$

Considering $J_{abcd} = -J_{badc}$

	$+\epsilon_{rqi}J_{1jrq}\omega_i\omega_j$	$-\epsilon_{rqi}J_{j1rq}\omega_i\omega_j$
ϵ_{123}	$+\cancel{J_{1212}}\omega_3\omega_2 + \cancel{J_{1312}}\omega_3\omega_3$	
ϵ_{132}	$-\cancel{J_{1213}}\omega_2\omega_2 - \cancel{J_{1313}}\omega_2\omega_3$	
ϵ_{213}		$+\cancel{J_{2121}}\omega_3\omega_2 + \cancel{J_{3121}}\omega_3\omega_3$
ϵ_{231}	$+\cancel{J_{1323}}\omega_1\omega_3$	$-\cancel{J_{2123}}\omega_1\omega_2$
ϵ_{321}	$-\cancel{J_{1232}}\omega_1\omega_2$	$+\cancel{J_{3132}}\omega_1\omega_3$
ϵ_{312}		$-\cancel{J_{2131}}\omega_2\omega_2 - \cancel{J_{3131}}\omega_2\omega_3$

We get

$$m'_s = I_{st} \frac{d\omega'_t(S', S)}{dt}$$

?????

◇

Let's try another approach. Start with **5.332**: $\frac{d}{dt}(I_{st}\omega_t) = M_s$

$$\frac{d}{dt}(I_{st}(S', S)\omega_t(S', S)) = M_s(S', S) \quad (10)$$

Cf. **5.408**.

$$\omega'_u(S', S) = A_{uq}\omega_q(S', S) \quad (11)$$

$$\times A_{ut} \rightarrow A_{ut}\omega'_u(S', S) = A_{ut}A_{uq}\omega_q(S', S) \quad (12)$$

$$= \omega_t(S', S) \quad (13)$$

$$\omega_t(S', S) = A_{ut}\omega'_u(S', S) \quad (14)$$

$$(10) \Rightarrow M_s(S', S) = \frac{d}{dt}(I_{st}(S', S)A_{ut}\omega'_u(S', S)) \quad (15)$$

$$\times A_{ps} \Rightarrow M'_p(S', S) = A_{ps}\frac{d}{dt}(I_{st}(S', S)A_{ut}\omega'_u(S', S)) \quad (16)$$

$$I_{st}(S', S) = A_{as}A_{bt}I'_{ab}(S', S) \quad (17)$$

$$(16) \Rightarrow M'_p(S', S) = A_{ps}\frac{d}{dt}(A_{as}A_{bt}I'_{ab}(S', S)A_{ut}\omega'_u(S', S)) \quad (18)$$

$$= A_{ps}\frac{d}{dt}(A_{as}I'_{ak}(S', S)\omega'_k(S', S)) \quad (19)$$

As we transformed $I_{st}(S', S)$ to a coordinate system fixed to the body we have that the elements of $I'_{ab}(S', S)$ are constants.

Hence,

$$M'_p(S', S) = I'_{ak}(S', S)A_{ps}\frac{d}{dt}(A_{as}\omega'_k(S', S)) \quad (20)$$

$$= I'_{ak}(S', S)A_{ps}(\dot{A}_{as}\omega'_k(S', S) + A_{as}\dot{\omega}'_k(S', S)) \quad (21)$$

$$= I'_{ak}(S', S)A_{ps}A_{as}\dot{\omega}'_k(S', S) + I'_{ak}(S', S)A_{ps}\dot{A}_{as}\omega'_k(S', S) \quad (22)$$

$$= I'_{pk}(S', S)\dot{\omega}'_k(S', S) + I'_{ak}(S', S)A_{ps}\dot{A}_{as}\omega'_k(S', S) \quad (23)$$

$$\mathbf{5.408.} \Rightarrow A_{ps}\dot{A}_{as} = \omega'_{ap}(S', S) \quad (24)$$

$$(23) \Rightarrow M'_p(S', S) = I'_{pk}(S', S)\dot{\omega}'_k(S', S) + I'_{ak}(S', S)\omega'_{ap}(S', S)\omega'_k(S', S) \quad (25)$$

Let's now calculate the last expression for $p = 1$

$$M'_1(S', S) = I'_{1k}(S', S)\dot{\omega}'_k(S', S) + I'_{ak}(S', S)\omega'_{a1}(S', S)\omega'_k(S', S) \quad (26)$$

As we want an arbitrary, fixed to the body of course, coordinate system, it is possible to chose one so that the $I'_{kj}(S', S) = 0$ for $k \neq j$ i.e. $I'_{kj}(S', S)$ is diagonal. This is possible because $I'_{kj}(S', S)$ is symmetric (the finite-dimensional spectral theorem says that any symmetric matrix whose entries are real can be diagonalized by an orthogonal matrix).

We get, noticing that $\omega'_{ab}(S', S)$ is skew-symmetric and hence $\omega'_{11}(S', S) = 0$:

$$M'_1(S', S) = I'_{11}(S', S)\dot{\omega}'_1(S', S) + I'_{22}(S', S)\omega'_{21}(S', S)\omega'_2(S', S) + I'_{33}(S', S)\omega'_{31}(S', S)\omega'_3(S', S) \quad (27)$$

Using **5.317**: $\omega'_{21}(S', S) = -\omega'_3(S', S)$ and $\omega'_{31}(S', S) = \omega'_2(S', S)$ we get the asked expression

$$M'_1(S', S) = I'_{11}(S', S)\dot{\omega}'_1(S', S) - \left(I'_{22}(S', S) - I'_{33}(S', S)\right)\omega'_2(S', S)\omega'_3(S', S) \quad (28)$$



5.13 p169 - Exercise

Assign convenient generalized coordinates for the three systems (a), (b), and (c) mentioned at the beginning of this section, and calculate the kinematical metric form in each case

(a) **a particle on a surface** ($N = 2$)

No need here for fancy general coordinates: the V_2 coordinate system in the plane is the metric form of choice. Indeed $|v|^2 = a_{mn}v_m v_n$ and for a V_2

$$ds^2 = \left(a_{11} (v^1)^2 + 2a_{12} v^1 v^2 + a_{22} (v^2)^2 \right) dt^2$$

and if the space is Euclidean and the plane smooth, we can choose an orthogonal system where a_{12} will vanish.

(b) **a rigid body which can turn about a fixed point, as in the preceding section** ($N = 3$)

For a rigid body we can choose a coordinate system S' fixed to the body to describe the geometry of the rigid body. The kinetic energy referenced to a 'non-moving' (abuse of language) coordinate system S is

$$T = \frac{1}{2} \sum \rho v'_n(S) v'_n(S) \quad (\text{summation over all masses in the rigid body}) \quad (1)$$

We know by **5.409**: $v'_n(S) = v'_n(S') + \omega'_{mn}(S', S) z'_m$. As the $v'_n(S')$ are fixed, we have $v'_n(S') = 0$ giving

$$T = \frac{1}{2} \sum \rho z'_m z'_k \omega'_{mn}(S', S) \omega'_{kn}(S', S) \quad (2)$$

Note in (2) that we bring $\omega'_{mn}(S', S)$ out of the summation as this expression is the same for all masses in the body.

$$\omega_{mn}(S', S) = \epsilon_{mnt} \omega'_t(S', S) \quad (3)$$

$$\Rightarrow T = \frac{1}{2} \sum \rho \epsilon_{mnt} \epsilon_{kns} z'_m z'_k \omega'_t(S', S) \omega'_s(S', S) \quad (4)$$

$$= \frac{1}{2} \sum \rho (\delta_{mk} \delta_{ts} - \delta_{ms} \delta_{kt}) z'_m z'_k \omega'_t(S', S) \omega'_s(S', S) \quad (5)$$

$$= \frac{1}{2} \sum \rho \left(z'_m z'_m \omega'_t(S', S) \omega'_t(S', S) - z'_s z'_t \omega'_t(S', S) \omega'_s(S', S) \right) \quad (6)$$

$$= \frac{1}{2} \sum \rho \left(\delta_{st} z'_m z'_m \omega'_s(S', S) \omega'_t(S', S) - z'_s z'_t \omega'_t(S', S) \omega'_s(S', S) \right) \quad (7)$$

$$= \frac{1}{2} \sum \rho \left(\delta_{st} z'_m z'_m - z'_s z'_t \right) \omega'_s(S', S) \omega'_t(S', S) \quad (8)$$

By **5.335**. we have $I_{st} = \delta_{st} \sum \rho z_m z_m - \sum \rho z_s z_t$ and so (8) can be written as

$$T = \frac{1}{2} I_{st} \omega'_s(S', S) \omega'_t(S', S) \quad (9)$$

So we can choose the three angles $\Omega'_s(S', S)$ with $(\omega'_s(S', S) = \frac{d\Omega'_s(S', S)}{dt})$ as generalized coordinates and define

$$ds^2 = I_{st} d\Omega'_s(S', S) d\Omega'_t(S', S)$$

with

$$a_{mn} = I_{mn}$$

having constants as elements. Some check on consistency of the metric tensor defined by (14):

Positive definite ? : Yes, as T is positive by construction.

Symmetric ? : Yes, as $a_{mn} = I_{km}$ and I_{km} is symmetric.

(c) **a chain of six rods smoothly hinged together, with one end fixed and all moving on a smooth plane** ($N = 6$)

To simplify the notation we will assume that the mass m_k of each rod (with length L_k) is concentrated at it's endpoint .

First we note that the velocity of a rod is composed of two vectors, one (labelled as \bar{v}_k) generated by its own rotation relative to the previous rod and the other (labelled as \bar{v}_{k-1}) generated by the velocity of the endpoint of the rod to which it is attached (see.fig. 5.2).

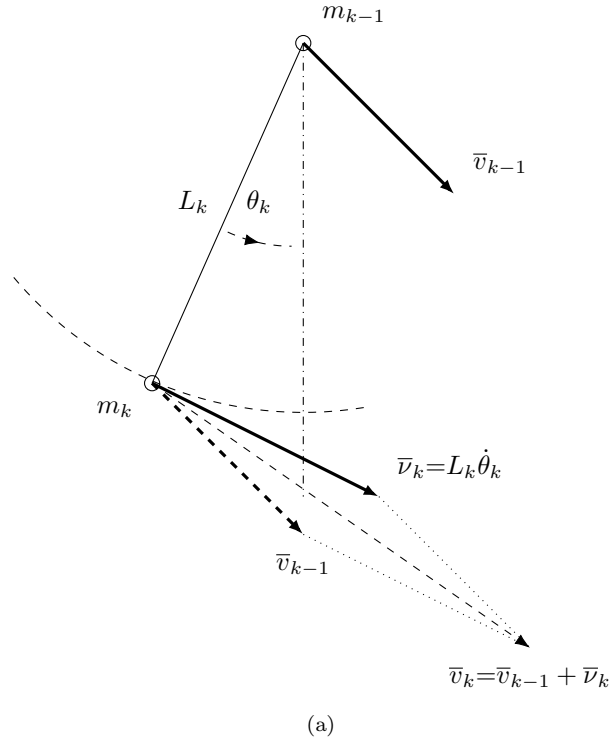


Figure 5.2: Composition of absolute and relative velocities of a chain of rods

If we take Cartesian coordinates it is easy to see that rod (1) will have components

$$\left(L_1 \dot{\theta}_1 \cos \theta, L_1 \dot{\theta}_1 \sin \theta_1 \right)$$

rod (2)

$$\left(L_1 \dot{\theta}_1 \cos \theta_1 + L_2 \dot{\theta}_2 \cos \theta_2, L_1 \dot{\theta}_1 \sin \theta_1 + L_2 \dot{\theta}_2 \sin \theta_2 \right)$$

\vdots

rod (k)

$$\left(\sum_{i=1}^k L_i \dot{\theta}_i \cos \theta_i, \sum_{i=1}^k L_i \dot{\theta}_i \sin \theta_i \right)$$

and so

$$\left(v^{(k)} \right)^2 = \left(\sum_{i=1}^k L_i \dot{\theta}_i \cos \theta_i \right)^2 + \left(\sum_{i=1}^k L_i \dot{\theta}_i \sin \theta_i \right)^2 \quad (10)$$

$$= \sum_{i=1}^k \left(L_i \dot{\theta}_i \right)^2 + 2 \sum_{i=1}^k \sum_{j=1}^{k-i} \left(L_i L_{i+j} \dot{\theta}_i \dot{\theta}_{i+j} \cos (\theta_i - \theta_{i+j}) \right) \quad (11)$$

So the kinetic energy of one rod and the total kinetic energy of the system are

$$T^{(k)} = \frac{1}{2} m_k \left[\sum_{i=1}^k \left(L_i \dot{\theta}_i \right)^2 + 2 \sum_{i=1}^k \sum_{j=1}^{k-i} \left(L_i L_{i+j} \dot{\theta}_i \dot{\theta}_{i+j} \cos (\theta_i - \theta_{i+j}) \right) \right] \quad (12)$$

$$T = \sum_{k=1}^N T^{(k)} \quad (13)$$

For $N = 6$ we get

rod	$T^{(k)}$
1	$\frac{1}{2} m_1 \left[\left(L_1 \dot{\theta}_1 \right)^2 \right]$
2	$\frac{1}{2} m_2 \left[\left(L_1 \dot{\theta}_1 \right)^2 + \left(L_2 \dot{\theta}_2 \right)^2 + 2 L_1 L_2 \dot{\theta}_1 \dot{\theta}_2 \cos (\theta_1 - \theta_2) \right]$
3	$\frac{1}{2} m_3 \left[\left(L_1 \dot{\theta}_1 \right)^2 + \left(L_2 \dot{\theta}_2 \right)^2 + \left(L_3 \dot{\theta}_3 \right)^2 + 2 L_1 L_2 \dot{\theta}_1 \dot{\theta}_2 \cos (\theta_1 - \theta_2) + 2 L_1 L_3 \dot{\theta}_1 \dot{\theta}_3 \cos (\theta_1 - \theta_3) + \dots \right]$
4	$\frac{1}{2} m_4 \left[\left(L_1 \dot{\theta}_1 \right)^2 + \left(L_2 \dot{\theta}_2 \right)^2 + \left(L_3 \dot{\theta}_3 \right)^2 + \left(L_4 \dot{\theta}_4 \right)^2 + 2 L_1 L_2 \dot{\theta}_1 \dot{\theta}_2 \cos (\theta_1 - \theta_2) + 2 L_1 L_3 \dot{\theta}_1 \dot{\theta}_3 \cos (\theta_1 - \theta_3) + \dots \right]$
5	$\frac{1}{2} m_5 \left[\left(L_1 \dot{\theta}_1 \right)^2 + \left(L_2 \dot{\theta}_2 \right)^2 + \left(L_3 \dot{\theta}_3 \right)^2 + \left(L_4 \dot{\theta}_4 \right)^2 + \left(L_5 \dot{\theta}_5 \right)^2 + 2 L_1 L_2 \dot{\theta}_1 \dot{\theta}_2 \cos (\theta_1 - \theta_2) + \dots \right]$
6	$\frac{1}{2} m_6 \left[\left(L_1 \dot{\theta}_1 \right)^2 + \left(L_2 \dot{\theta}_2 \right)^2 + \left(L_3 \dot{\theta}_3 \right)^2 + \left(L_4 \dot{\theta}_4 \right)^2 + \left(L_5 \dot{\theta}_5 \right)^2 + \left(L_6 \dot{\theta}_6 \right)^2 + 2 L_1 L_2 \dot{\theta}_1 \dot{\theta}_2 \cos (\theta_1 - \theta_2) + \dots \right]$

Giving for T

$$2T = \left\{ \begin{array}{l} (m_1 + m_2 + m_3 + m_4 + m_5 + m_6) \left(L_1 \dot{\theta}_1 \right)^2 \\ + (m_2 + m_3 + m_4 + m_5 + m_6) \left(L_2 \dot{\theta}_2 \right)^2 \\ + (m_3 + m_4 + m_5 + m_6) \left(L_3 \dot{\theta}_3 \right)^2 \\ + (m_4 + m_5 + m_6) \left(L_4 \dot{\theta}_4 \right)^2 \\ + (m_5 + m_6) \left(L_5 \dot{\theta}_5 \right)^2 \\ + (m_6) \left(L_6 \dot{\theta}_6 \right)^2 \\ + 2(m_2 + m_3 + m_4 + m_5 + m_6) L_1 L_2 \dot{\theta}_1 \dot{\theta}_2 \cos(\theta_1 - \theta_2) \\ + 2(m_3 + m_4 + m_5 + m_6) L_1 L_3 \dot{\theta}_1 \dot{\theta}_3 \cos(\theta_1 - \theta_3) \\ + 2(m_3 + m_4 + m_5 + m_6) L_2 L_3 \dot{\theta}_2 \dot{\theta}_3 \cos(\theta_2 - \theta_3) \\ + 2(m_4 + m_5 + m_6) L_1 L_4 \dot{\theta}_1 \dot{\theta}_4 \cos(\theta_1 - \theta_4) \\ + 2(m_4 + m_5 + m_6) L_2 L_4 \dot{\theta}_2 \dot{\theta}_4 \cos(\theta_2 - \theta_4) \\ + 2(m_4 + m_5 + m_6) L_3 L_4 \dot{\theta}_3 \dot{\theta}_4 \cos(\theta_3 - \theta_4) \\ + 2(m_5 + m_6) L_1 L_5 \dot{\theta}_1 \dot{\theta}_5 \cos(\theta_1 - \theta_5) \\ + 2(m_5 + m_6) L_2 L_5 \dot{\theta}_2 \dot{\theta}_5 \cos(\theta_2 - \theta_5) \\ + 2(m_5 + m_6) L_3 L_5 \dot{\theta}_3 \dot{\theta}_5 \cos(\theta_3 - \theta_5) \\ + 2(m_5 + m_6) L_4 L_5 \dot{\theta}_4 \dot{\theta}_5 \cos(\theta_4 - \theta_5) \\ + 2(m_6) L_1 L_6 \dot{\theta}_1 \dot{\theta}_6 \cos(\theta_1 - \theta_6) \\ + 2(m_6) L_2 L_6 \dot{\theta}_2 \dot{\theta}_6 \cos(\theta_2 - \theta_6) \\ + 2(m_6) L_3 L_6 \dot{\theta}_3 \dot{\theta}_6 \cos(\theta_3 - \theta_6) \\ + 2(m_6) L_4 L_6 \dot{\theta}_4 \dot{\theta}_6 \cos(\theta_4 - \theta_6) \\ + 2(m_6) L_5 L_6 \dot{\theta}_5 \dot{\theta}_6 \cos(\theta_5 - \theta_6) \end{array} \right. \quad (14)$$

We define as general coordinates the angles θ^i and express ds^2 as

$$ds^2 = 2T dt^2$$

and see that ds^2 is of the required form

$$ds^2 = a_{mn} d\theta^m d\theta^n$$

The metric tensor a_{mn} contains elements depending on the θ_k chosen as general coordinates of the system and is a good candidate as metric tensor. Some check on consistency of the metric tensor defined by (14):

Positive definite ? : Yes, as T is positive by definition

Symmetric ? : Yes, as the non-diagonal term a_{ij} contains $\cos(\theta_i - \theta_j) = \cos(\theta_j - \theta_i)$

Number of elements : the metric tensor a_{mn} for $N = 6$ should contain 6 diagonal elements and $\frac{6 \times 6 - 6}{2} = 15$ independent non-diagonal elements. Checking (8), one can find that the numbers yield.



5.14 p174 - Exercise

Establish the general result

$$v \frac{dv}{ds} = X_r \lambda^r, \quad \kappa v^2 = X_r \nu^r$$

Deduce that, if no forces act on the system, the trajectory is a geodesic in configuration space and the magnitude of the velocity is constant.

In configuration space $f_r = X_r$. Hence by **5, 515**

$$X^r = v \frac{dv}{ds} \lambda^r + \kappa v^2 \nu^r \quad (1)$$

$$\Rightarrow \quad X^r \lambda_r = X_r \lambda^r = v \frac{dv}{ds} \quad \text{as } \lambda^r \perp \nu^r \quad (2)$$

$$\text{and} \quad X^r \nu_r = X_r \nu^r = \kappa v^2 \quad \text{as } \lambda^r \perp \nu^r \quad (3)$$

$$(4)$$

The trajectory is a geodesic if $\kappa = 0$ which is the case as $X_r = 0$ and

$$v \frac{dv}{ds} = 0 \Rightarrow \frac{dv}{ds} = 0 \Rightarrow v = C^t$$



5.15 p174 - Clarification

It is easy to see that the lines of force are the orthogonal trajectories of the equipotential surface $V = C^t$

Consider a curve given by $x^r = x^r(u)$.

Along that line we have $V = V(x^r(u))$. Take $u = s$ as parameter and let's impose that $V(s) = C^t$.

We have $\frac{dV}{ds} = \frac{\partial V}{\partial x^r} \frac{dx^r}{ds} = \frac{\partial V}{\partial x^r} \lambda^r = 0$ with $\lambda^r = \frac{dx^r}{ds}$ the tangent vector along that curve.

But $X_r = \frac{\partial V}{\partial x^r}$.

So, $X_r \lambda^r = 0$ and as X_r is collinear with dx^r (the infinitesimal line element of the line of force) we have $dx_n \lambda^n = a_{mn} dx^m \lambda^n = 0$ proving the perpendicularity of both curves.



5.16 p176 - Exercise

For a spherical pendulum, show that the lines of force are geodesics on the sphere on which the particle is constrained to move. What does the theorem stated above tell us in this case?

For the spherical pendulum we have the following situation

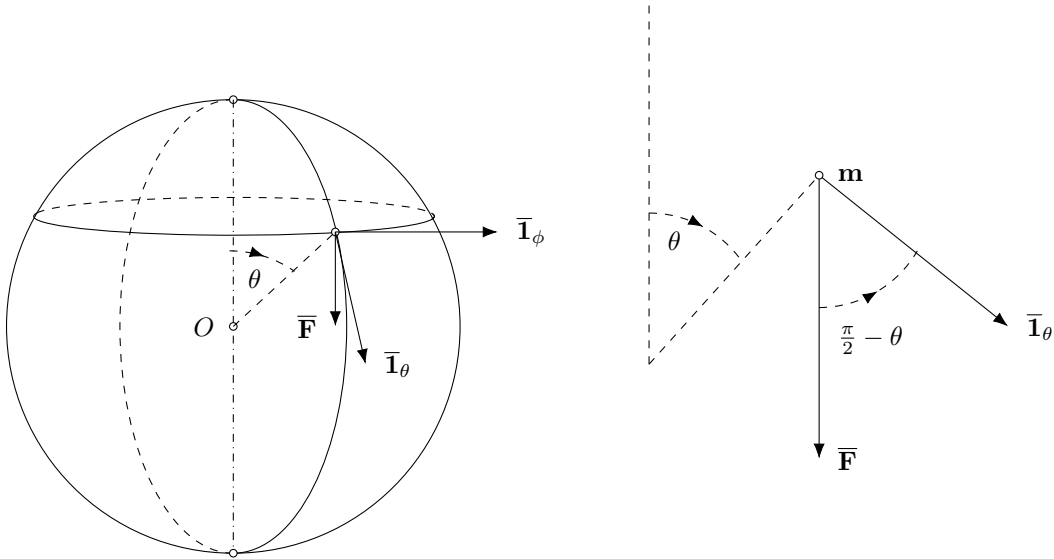


Figure 5.3: Physical components of the gravitational force tensor acting on a mass \mathbf{m} on a sphere

From the figure it is clear that the only component of the gravitational force acting on the mass is restricted along the $\bar{\mathbf{I}}_\theta$ vector which, with varying θ lays along a great circle of the sphere which is a geodesic. Hence the lines of force are great circle on the sphere.

For the theorem stated this means that as a mass is launched along a great circle, it will stay on that great circle.



5.17 p176 - Exercise

A system starts from rest at a configuration O . Prove that the trajectory at O is tangent to the line of force through O , and that the first curvature of the trajectory is one-third of the first curvature of the line of force.

From 5.533 we have

$$v \frac{dv}{ds} = X_r \lambda^r, \quad \kappa v^2 = X_r \nu^r \quad (1)$$

From the second expression we have as $v = 0$ at O that $X_r \nu^r = 0$, meaning that X_r is perpendicular to ν^r . Also by 5.516

$$f^r = \frac{dv}{dt} \lambda^r + \kappa v^2 \nu^r \quad (2)$$

we know that the acceleration lies in the elementary two-space containing the tangent and the first normal to the trajectory implying by the previous result that X_r and λ^r are collinear. Note that from (1) we can not conclude (because $v = 0$) from the first expression that $X_r \lambda^r = 0$. Indeed, $v \frac{dv}{ds}$ is a derived expression form of $\frac{dv}{dt}$. As $\frac{dv}{dt}$ is not necessarily 0 (otherwise the system would for ever stay on the configuration at O meaning that $ds = 0$, making the expression $v \frac{dv}{ds}$ meaningless.)

Let's consider (2) with $f^r = X^r$:

$$\frac{dv}{dt} \lambda^r + \kappa v^2 \nu^r = X^r \quad (3)$$

We know that at O , X^r is tangent to the trajectory and so $X^r = X \lambda^r$. At the same point we can also define $X^r = X \lambda'^r$, with λ'^r the tangent vector to the line of force. Multiplying (3) with λ^r we see that $\frac{dv}{dt} = X$. So we get for (3)

$$X \lambda^r + \kappa v^2 \nu^r = X \lambda'^r \quad (4)$$

$$\begin{aligned} \frac{\delta(4)}{\delta s} \Rightarrow \frac{dX}{ds} \lambda^r + X \underbrace{\frac{\delta \lambda^r}{\delta s}}_{\kappa \nu^r} + \frac{d\kappa}{ds} \underbrace{v^2}_{=0} \nu^r + 2\kappa \underbrace{v \frac{dv}{ds}}_{=\frac{dv}{dt}=X} \nu^r + \kappa \underbrace{v^2}_{=0} \frac{\delta \nu^r}{\delta s} &= \frac{dX}{ds} \lambda'^r + X \underbrace{\frac{\delta \lambda'^r}{\delta s}}_{=\kappa' \nu'^r} \Rightarrow 3\kappa = \end{aligned} \quad (5)$$

(we evaluate the expression at point O and define $\kappa' \nu'^r$ as the first curvature tensor of the line of force evaluated at 0)

$$\frac{dX}{ds} \lambda^r + X \kappa \nu^r + 2\kappa X \nu^r = \frac{dX}{ds} \lambda'^r + X \nu'^r \quad (6)$$

$$\times \nu^r \Rightarrow 3\kappa X = \frac{dX}{ds} \underbrace{\lambda'^r \nu^r}_{=0} + X \kappa' \nu'^r \nu^r \quad (7)$$

$$\Rightarrow 3\kappa = \kappa' \nu'^r \nu^r \quad (8)$$

Note that $\lambda'^r \nu^r = 0$ as λ'^r coincides with λ^r . On the other hand we still have to prove that ν'^r coincides with ν^r at O .

$$(6) \times \nu'^r \Rightarrow X\kappa\nu^r\nu'^r + 2\kappa X\nu^r\nu'^r = X\kappa' \quad (9)$$

$$3\kappa\nu^r\nu'^r = \kappa' \quad (10)$$

From (8) and (10) we see that $\nu^r\nu'^r = 1$ and so

$$3\kappa = \kappa'$$



5.18 p181-p182 - Clarification Figures 13., 14. and 15.

There are several ways to perform a map of the configuration space of a rigid body with fixed point.

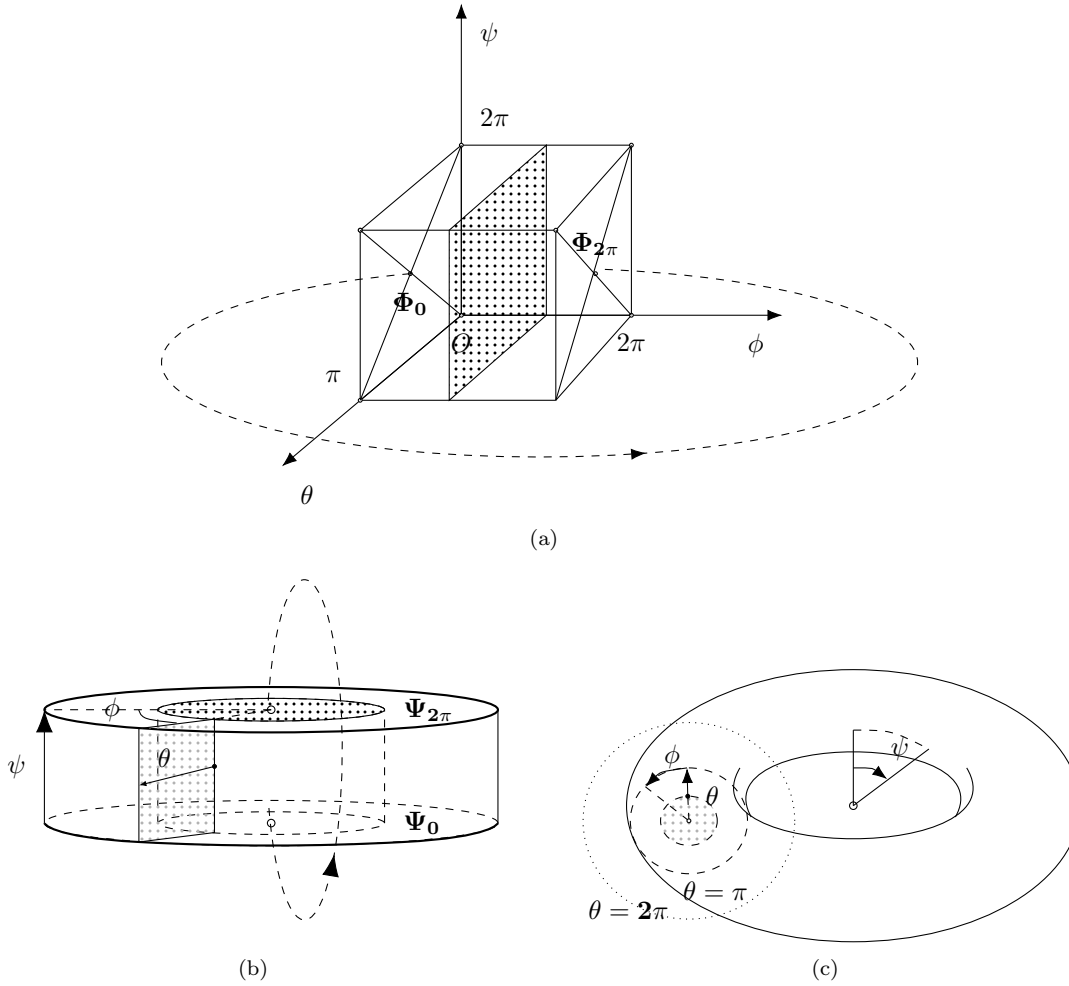


Figure 5.4: Map of the configuration space of a rigid body with fixed point.

Consider figure 5.2(a). We can stretch like an accordion the cuboid along the ϕ axis and bent it so that the planes $\phi = 0$ and $\phi = 2\pi$ join. We get (b), a torus with square sections. The dimension ϕ is dealt with as a point $P(\theta, \phi, \psi)$ in the configuration space returns to the same point when varying ϕ to $\phi + 2k\pi$.

We can apply the same procedure of stretching and bending for the ψ dimension so that the planes $\Psi = 0$ and $\Psi = 2\pi$ join. We get (c), a torus-like object.

The only dimension left is θ which our multi-dimensional crippled mind can't find a way to reshape this pseudo-torus so that when varying θ we can come back to the same point as started.



5.19 p183 - Clarification for 5.561

The kinetic energy is

$$\mathbf{5.561.} \quad T = \frac{1}{2}I \left(\dot{\theta}^2 + \dot{\phi}^2 + \dot{\psi}^2 + 2\dot{\phi}\dot{\psi} \cos \theta \right)$$

We first determine the general form of the kinetic energy for a rigid body rotating around a fixed point. From **5, 310** we have

$$v_r = -\omega_{rm} z_m = -\epsilon_{rst} \omega_s z_t \quad (1)$$

$$T = \frac{1}{2} \sum m v_r v_r \quad (2)$$

$$\Rightarrow T = \frac{1}{2} \sum m \epsilon_{rst} \omega_s z_t \epsilon_{ruv} \omega_u z_v \quad (3)$$

$$= \frac{1}{2} \sum m (\delta_{su} \delta_{tv} \omega_s \omega_u z_t z_v - \delta_{sv} \delta_{tu} \omega_s \omega_u z_t z_v) \quad (4)$$

For the case $N = 3$ we get from (4):

$$T = \frac{1}{2} \sum m [\omega_1^2 (z_2^2 + z_3^2) + \omega_2^2 (z_1^2 + z_3^2) + \omega_3^2 (z_1^2 + z_2^2) - 2\omega_1 \omega_2 z_1 z_2 - 2\omega_1 \omega_3 z_1 z_3 - 2\omega_2 \omega_3 z_2 z_3] \quad (5)$$

Using the result from **5.336** this can be written as

$$T = \frac{1}{2} [I_{11} \omega_1^2 + I_{22} \omega_2^2 + I_{33} \omega_3^2 + 2I_{12} \omega_1 \omega_2 + 2I_{13} \omega_1 \omega_3 + 2I_{23} \omega_2 \omega_3] \quad (6)$$

Considering that the matrix I_{ij} is symmetric, one can always find an appropriate basis so that the matrix becomes diagonal. Hence (6) can be simplified to

$$T = \frac{1}{2} [I_{11} \omega_1^2 + I_{22} \omega_2^2 + I_{33} \omega_3^2] \quad (7)$$

Of course the ω_i in (7) are not the Euler angles and we have to express the ω_i as functions of the Euler angles.

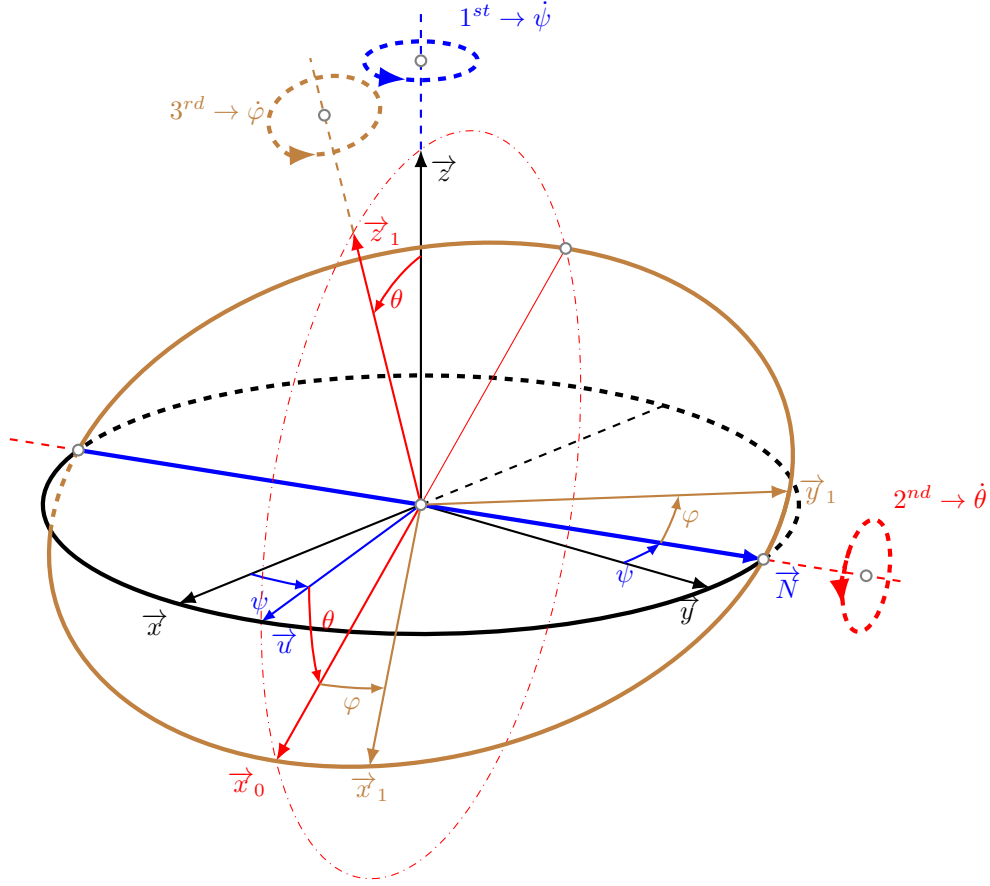


Figure 5.5: Euler angles

Consider the Euler angles as in figure 5.5. The resulting angular velocity of the rigid body can be expressed as

$$\bar{\omega} = \dot{\psi} \bar{z} + \dot{\theta} \bar{N} + \dot{\phi} \bar{z}_1 \quad (8)$$

The projection of $\bar{\omega}$ on the basis $\bar{x}_1, \bar{y}_1, \bar{z}_1$ (which we choose fixed to the rigid body) will then coincide with the ω_i .

We determine the components of $\bar{z}, \bar{N}, \bar{z}_1$ with $\bar{x}_1, \bar{y}_1, \bar{z}_1$ as basis.

We have

$$\begin{cases} \bar{N} = \cos \phi \bar{y}_1 + \sin \phi \bar{x}_1 \\ \bar{z} = \cos \theta \bar{z}_1 - \sin \theta \bar{x}_0 \\ \bar{x}_0 = \cos \phi \bar{x}_1 - \sin \phi \bar{y}_1 \end{cases} \quad (9)$$

$$\Rightarrow \begin{cases} \bar{N} = \cos \phi \bar{y}_1 + \sin \phi \bar{x}_1 \\ \bar{z} = \cos \theta \bar{z}_1 - \sin \theta \cos \phi \bar{x}_1 + \sin \theta \sin \phi \bar{y}_1 \end{cases} \quad (10)$$

Hence,

$$\bar{\omega} = \dot{\psi} \cos \theta \bar{z}_1 - \dot{\psi} \sin \theta \cos \phi \bar{x}_1 + \dot{\psi} \sin \theta \sin \phi \bar{y}_1 + \dot{\theta} \cos \phi \bar{y}_1 + \dot{\theta} \sin \phi \bar{x}_1 + \dot{\phi} \bar{z}_1 \quad (11)$$

giving

$$\begin{cases} \omega_1 = \dot{\theta} \sin \phi - \dot{\psi} \sin \theta \cos \phi \\ \omega_2 = \dot{\psi} \sin \theta \sin \phi + \dot{\theta} \cos \phi \\ \omega_3 = \dot{\psi} \cos \theta + \dot{\phi} \end{cases} \quad (12)$$

In the case considered $I_{11} = I_{22} = I_{33} = I$. Plugging (12) in (7) gives indeed

$$T = \frac{1}{2} I \left(\dot{\theta}^2 + \dot{\phi}^2 + \dot{\psi}^2 + 2\dot{\phi}\dot{\psi} \cos \theta \right)$$

◆

5.20 p186 - Exercise 1

If a vector at the point with coordinates $(1, 1, 1)$ in Euclidean 3-space has components $(3, -1, 2)$, find the contra-variant, covariant and physical components in spherical polar coordinates.

The tensor T_n to consider is $(3, -1, 2) - (1, 1, 1) = (2, -2, 1)$.

The Jacobian matrix for the transformation $z^n \rightarrow x^k$, evaluated at the point $(1, 1, 1)$ is

$$J_{(1,1,1)} = \begin{pmatrix} \frac{x}{r} & \frac{y}{r} & \frac{z}{r} \\ \frac{xz}{r^2\sqrt{x^2+y^2}} & \frac{yz}{r^2\sqrt{x^2+y^2}} & \frac{-(x^2+y^2)}{r^2\sqrt{x^2+y^2}} \\ \frac{-y}{x^2+y^2} & \frac{x}{x^2+y^2} & 0 \end{pmatrix} \quad (1)$$

$$= \begin{pmatrix} \frac{1}{\sqrt{3}} & \frac{1}{\sqrt{3}} & \frac{1}{\sqrt{3}} \\ \frac{1}{3\sqrt{2}} & \frac{1}{3\sqrt{2}} & -\frac{\sqrt{2}}{3} \\ -\frac{1}{2} & \frac{1}{2} & 0 \end{pmatrix} \quad (2)$$

$$\Rightarrow \begin{pmatrix} r \\ \theta \\ \phi \end{pmatrix}_{T'n} = \begin{pmatrix} \frac{1}{\sqrt{3}} & \frac{1}{\sqrt{3}} & \frac{1}{\sqrt{3}} \\ \frac{1}{3\sqrt{2}} & \frac{1}{3\sqrt{2}} & -\frac{\sqrt{2}}{3} \\ -\frac{1}{2} & \frac{1}{2} & 0 \end{pmatrix} \begin{pmatrix} 2 \\ -2 \\ 1 \end{pmatrix} \quad (3)$$

$$= \begin{pmatrix} \frac{1}{\sqrt{3}} \\ -\frac{\sqrt{2}}{3} \\ -2 \end{pmatrix} \quad (4)$$

We have the metric tensor evaluated at $(1, 1, 1)$

$$a_{mn} = \begin{pmatrix} 1 & 0 & 0 \\ 0 & r^2 & 0 \\ 0 & 0 & r^2 \sin^2 \theta \end{pmatrix} = \begin{pmatrix} 1 & 0 & 0 \\ 0 & 3 & 0 \\ 0 & 0 & 2 \end{pmatrix} \quad (5)$$

$$\Rightarrow \begin{pmatrix} r \\ \theta \\ \phi \end{pmatrix}_{T'_n} = \begin{pmatrix} 1 & 0 & 0 \\ 0 & 3 & 0 \\ 0 & 0 & 2 \end{pmatrix} \begin{pmatrix} \frac{1}{\sqrt{3}} \\ \frac{\sqrt{2}}{3} \\ -2 \end{pmatrix} \quad (6)$$

$$= \begin{pmatrix} \frac{1}{\sqrt{3}} \\ -\sqrt{2} \\ -4 \end{pmatrix} \quad (7)$$

And the physical components

$$\begin{pmatrix} r \\ \theta \\ \phi \end{pmatrix}_{T'_{ph.}} = \begin{pmatrix} 1 & 0 & 0 \\ 0 & \frac{1}{\sqrt{3}} & 0 \\ 0 & 0 & \frac{1}{\sqrt{2}} \end{pmatrix} \begin{pmatrix} \frac{1}{\sqrt{3}} \\ -\sqrt{2} \\ -4 \end{pmatrix} \quad (8)$$

$$= \begin{pmatrix} \frac{1}{\sqrt{3}} \\ -\sqrt{\frac{2}{3}} \\ -2\sqrt{2} \end{pmatrix} \quad (9)$$

Another way to find the physical components is to project orthogonally the tensor on the unit vectors of a local Cartesian coordinate system, oriented along the unit vectors $\bar{e}_r, \bar{e}_\theta, \bar{e}_\phi$ corresponding to the vector $P(1, 1, 1)$ with modulus $|P| = \sqrt{3}$. We have for the tensor $T_n(2, -2, 1)$ with modulus $|T_n| = 3$ as component along \bar{e}_r :

$$|T_n| \cos \alpha = |T_n| \frac{\langle T_n, P \rangle}{|T_n| |P|} \quad (10)$$

$$= |T_n| \frac{2 - 2 + 1}{|T_n| |P|} \quad (11)$$

$$= \frac{1}{\sqrt{3}} \quad (12)$$

For the component along \bar{e}_θ we first have to determine the vector \bar{e}_θ . As first equation we have the

orthogonality condition with \bar{e}_r and putting $\bar{e}_\theta = (a, b, c)$, get $\langle \bar{e}_r, \bar{e}_\theta \rangle = a + b + c = 0$. As \bar{e}_θ lies in the plane $(1, 1, 0) - (0, 0, 0) - (0, 0, 1)$ we can put $a = b$ and get $\bar{e}_\theta = \frac{1}{\sqrt{6}}(1, 1, -2)$ and get for the tensor $T_n(2, -2, 1)$ as component along \bar{e}_θ :

$$|T_n| \cos \beta = |T_n| \frac{\langle T_n, \bar{e}_\theta \rangle}{|T_n|} \quad (13)$$

$$= |T_n| \frac{2 - 2 - 2}{|T_n| \sqrt{6}} \quad (14)$$

$$= -\frac{\sqrt{2}}{\sqrt{3}} \quad (15)$$

For the component along \bar{e}_ϕ we first have to determine the vector \bar{e}_ϕ . As first equation we have the orthogonality condition with the pair $\bar{e}_r, \bar{e}_\theta$ and get $\bar{e}_\phi = \bar{e}_r \times \bar{e}_\theta = \frac{1}{\sqrt{3}\sqrt{6}}(-3, 3, 0) = \left(-\frac{1}{\sqrt{2}}, \frac{1}{\sqrt{2}}, 0\right)$. For the tensor $T_n(2, -2, 1)$ as component along \bar{e}_ϕ :

$$|T_n| \cos \gamma = |T_n| \frac{\langle T_n, \bar{e}_\phi \rangle}{|T_n|} \quad (16)$$

$$= |T_n| \frac{-2 - 2}{|T_n| \sqrt{2}} \quad (17)$$

$$= -\frac{4}{\sqrt{2}} \quad (18)$$

$$= -2\sqrt{2} \quad (19)$$

giving

$$\begin{pmatrix} r \\ \theta \\ \phi \end{pmatrix}_{T'_{ph.}} = \begin{pmatrix} 1 \\ \frac{\sqrt{3}}{\sqrt{2}} \\ -\sqrt{\frac{2}{3}} \\ -2\sqrt{2} \end{pmatrix} \quad (20)$$

as in (9).



5.21 p186 - Exercise 2

In cylindrical coordinates (r, ϕ, z) in Euclidean 3-space, a vector field is such that the vector at each point points along the parametric line of ϕ , in the sense of ϕ increasing, and its magnitude is kr , where k is a constant. Find the contra-variant, covariant and physical components of this vector field.

We can work backwards, with the physical components as starting point. Indeed, at a point $P(r, \phi, z)$ the tensor of this vector field will have $(0, kr, 0)$ as physical components in the cylindrical coordinates (r, ϕ, z) system.

We have the metric tensor

$$a_{mn} = \begin{pmatrix} 1 & 0 & 0 \\ 0 & r^2 & 0 \\ 0 & 0 & 1 \end{pmatrix} \quad (1)$$

Giving

$$\begin{cases} X_1 = h_1 X_1^{phys.} = 0 \\ X_2 = h_2 X_2^{phys.} = kr^2 \\ X_3 = h_3 X_3^{phys.} = 0 \end{cases} \quad (2)$$

and

$$\begin{cases} X^1 = \frac{X_1^{phys.}}{h_1} = 0 \\ X^2 = \frac{X_2^{phys.}}{h_2} = k \\ X^3 = \frac{X_3^{phys.}}{h_3} = 0 \end{cases} \quad (3)$$



5.22 p186 - Exercise 3

Find the physical components of velocity and acceleration along the parametric lines of cylindrical coordinates in terms of the and their derivatives with respect to time.

We have the metric tensor

$$a_{mn} = \begin{pmatrix} 1 & 0 & 0 \\ 0 & r^2 & 0 \\ 0 & 0 & 1 \end{pmatrix} \quad (1)$$

and the contravariant velocities

$$\begin{cases} v^1 = \frac{dr}{dt} \\ v^2 = \frac{d\phi}{dt} \\ v^3 = \frac{dz}{dt} \end{cases} \quad (2)$$

giving by $v_K^{phys.} = h_K v^K$

$$\begin{cases} v_r = \frac{dr}{dt} \\ v_\phi = r \frac{d\phi}{dt} \\ v_z = \frac{dz}{dt} \end{cases} \quad (3)$$

For the acceleration using $f^r = \frac{\delta v^r}{\delta t}$ and the Christoffel symbols being

$$\begin{cases} \Gamma_{nk}^m = 0 \quad \forall \quad (nk) \neq (r, \theta), (\theta, \theta) \\ \Gamma_{r\theta}^\theta = \frac{1}{r} \quad \text{and} \quad \Gamma_{\theta\theta}^r = -r \end{cases} \quad (4)$$

we have

$$\left\{ \begin{array}{l} f^1 = \frac{dv^1}{dt} - \underbrace{r v^2 \frac{dx^2}{dt}}_{=(v^2)^2} \\ f^2 = \frac{dv^2}{dt} + \underbrace{\frac{1}{r} v^1 \frac{dx^2}{dt} + \frac{1}{r} v^2 \frac{dx^2}{dt}}_{=\frac{2}{r} v^1 v^2} \\ f^3 = \frac{dv^3}{dt} \end{array} \right. \quad (5)$$

giving by $f_K^{phys.} = h_K f^K$

$$\left\{ \begin{array}{l} f_r = \frac{dv^1}{dt} - r (v^2)^2 \\ f_{phi} = r \frac{dv^2}{dt} + r \frac{2}{r} v^1 v^2 \\ f_z = \frac{dv^3}{dt} \end{array} \right. \quad (6)$$

$$\Rightarrow \left\{ \begin{array}{l} f_r = \frac{d^2 r}{dt^2} - r \left(\frac{d\phi}{dt} \right)^2 \\ f_{phi} = r \frac{d^2 \phi}{dt^2} + 2 \frac{dr}{dt} \frac{d\phi}{dt} \\ f_z = \frac{d^2 z}{dt^2} \end{array} \right. \quad (7)$$

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5.23 p186 - Exercise 4

A particle moves on a sphere under the action of gravity. Find the contra-variant and co-variant components of the force, using colatitude and azimuth, and write down the equation of motion.

We determine first the physical components of the force.

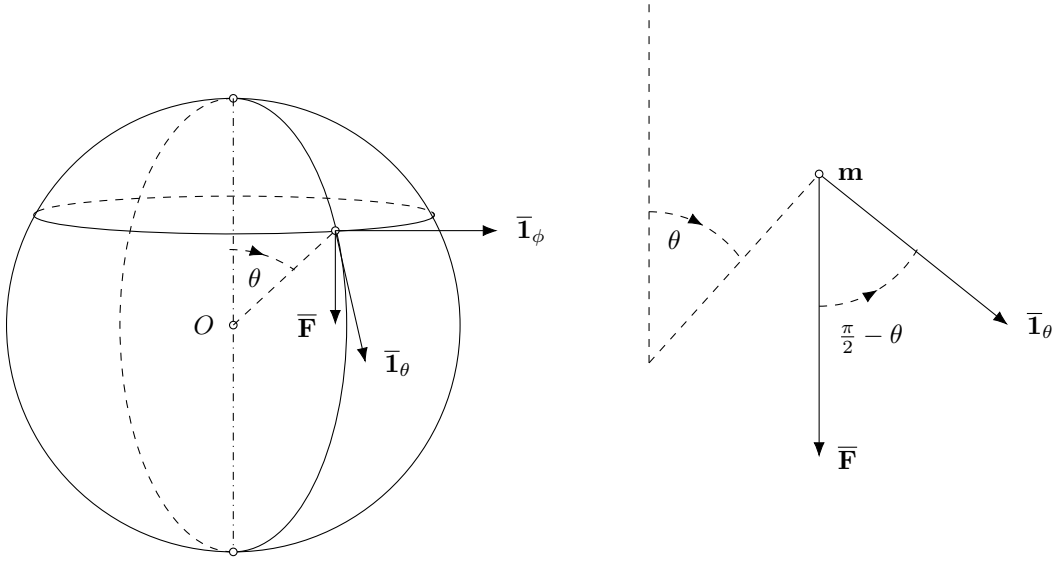


Figure 5.6: Physical components of the gravitational force tensor acting on a mass \mathbf{m} on a sphere

We note first that the unit vector $\bar{\mathbf{I}}_\phi$ is perpendicular to the plane formed by the vectors $\bar{\mathbf{I}}_\theta, \bar{\mathbf{F}}$ and so the force has no components projected on this vector. The vector $\bar{\mathbf{F}}$ is parallel with the axis of reference of the sphere with radius R and so the physical components become

$$\Rightarrow \begin{cases} F_\phi^{phys} = 0 \\ F_\theta^{phys} = mg \sin \theta \end{cases} \quad (1)$$

$$\Rightarrow \begin{cases} F^\phi = 0 & F_\phi = 0 \\ F^\theta = \frac{1}{R} mg \sin \theta & F_\theta = R mg \sin \theta \end{cases} \quad (2)$$

We use equation 5.212.

$$\begin{cases} \frac{d}{dt} \frac{\partial T}{\partial \dot{x}^s} - \frac{\partial T}{\partial x^s} = F_s \\ T = \frac{1}{2} m a_{pq} \dot{x}^p \dot{x}^q, \quad \dot{x}^s = \frac{dx^s}{dt} \end{cases} \quad (3)$$

with for our case

$$T = \frac{1}{2}mR^2 \left(\dot{\theta}^2 + \sin^2 \theta \dot{\phi}^2 \right) \quad (4)$$

and get the set of equation of motion (the second column gives the dimensional analysis as a check for consistency)

$$\left\{ \begin{array}{l} \frac{\ddot{\phi}}{\dot{\phi}} = -2 \cot \theta \dot{\theta} \quad : \quad \frac{[T]^{-2}}{[T]^{-1}} \cong [T]^{-1} \\ \ddot{\theta} - \left(\dot{\phi} \right)^2 \sin \theta \cos \theta = \frac{g}{R} \sin \theta \quad : \quad [T]^{-2} + ([T]^{-1})^2 \cong \frac{[L][T]^{-2}}{[L]} \end{array} \right. \quad (5)$$

Let's check the special case when $\dot{\phi} = 0$.

The first equation can be rewritten and gives of course $\phi = C$ while the second equation becomes

$$\ddot{\theta} = \frac{g}{R} \sin \theta$$

which is similar to the equation of the simple gravity pendulum.



5.24 p186 - Exercise 5

Consider the motion of a particle on a smooth torus under no forces except normal reaction. The geometrical line element may be written

$$ds^2 = (a - b \cos \theta)^2 d\phi^2 + b^2 d\theta^2$$

where ϕ is an azimuthal angle and θ an angular displacement from the equatorial plane. Show that the path of a particle satisfies the following two differential equations in which h is a constant

$$(a) \quad (a - b \cos \theta)^2 \frac{d\phi}{ds} = h$$

$$(b) \quad b^2 \left(\frac{d\theta}{d\phi} \right)^2 = \frac{(a - b \cos \theta)^4}{h^2} - (a - b \cos \theta)^2$$

We use equation 5.212. and 5.212.

$$\begin{cases} \frac{d}{dt} \frac{\partial T}{\partial \dot{x}^s} - \frac{\partial T}{\partial x^s} = F_s \\ T = \frac{1}{2} m a_{pq} \dot{x}^p \dot{x}^q, \quad \dot{x}^s = \frac{dx^s}{dt} \end{cases} \quad (1)$$

with for our case

$$T = \frac{1}{2} m \left(b^2 \dot{\theta}^2 + (a - b \cos \theta)^2 \dot{\phi}^2 \right) \quad (2)$$

$$\begin{cases} \frac{\partial T}{\partial \dot{\phi}} = m (a - b \cos \theta)^2 \dot{\phi} & \frac{\partial T}{\partial \phi} = 0 \\ \frac{\partial T}{\partial \dot{\theta}} = m b^2 \dot{\theta} & \frac{\partial T}{\partial \theta} = m b (a - b \cos \theta) \dot{\phi}^2 \sin \theta \end{cases} \quad (3)$$

giving

$$\begin{cases} (a - b \cos \theta)^2 \ddot{\phi} + 2b (a - b \cos \theta) \dot{\theta} \dot{\phi} \sin \theta = 0 \\ b^2 \ddot{\theta} - b (a - b \cos \theta) \dot{\phi}^2 \sin \theta = 0 \end{cases} \quad (4)$$

$$\Rightarrow \begin{cases} (a - b \cos \theta) \ddot{\phi} = -2b \dot{\theta} \dot{\phi} \sin \theta \\ b^2 \ddot{\theta} - b (a - b \cos \theta) \dot{\phi}^2 \sin \theta = 0 \end{cases} \quad (5)$$

In the first equation, put $y \equiv \dot{\phi}$ giving for the first equation:

$$\frac{dy}{y} = -2b \frac{\sin \theta d\theta}{(a - b \cos \theta)} \quad (6)$$

$$\Leftrightarrow \frac{dy}{y} = -2 \frac{d(a - b \cos \theta)}{(a - b \cos \theta)} \quad (7)$$

$$\Rightarrow \log y = -2 \log(a - b \cos \theta) + \log C \quad (8)$$

$$\Rightarrow \dot{\phi} = C (a - b \cos \theta)^{-2} \quad (9)$$

Note that $\dot{\phi}$ is a time derivative. But as we are on a geodesic, **5.226.** stands and so v is constant as $\frac{dv}{ds} = 0$. Using $v = \frac{ds}{dt}$, (9) can be written as

$$(a - b \cos \theta)^2 \frac{d\phi}{dt} = C \quad (10)$$

$$\Leftrightarrow (a - b \cos \theta)^2 \frac{d\phi}{ds} \underbrace{\frac{ds}{dt}}_{=v} = C \quad (11)$$

$$\Leftrightarrow (a - b \cos \theta)^2 \frac{d\phi}{ds} = h \quad \text{with } h = \frac{C}{v} \quad (12)$$

Next, we don't use the second equation in (5) but the line element equation instead

$$ds^2 = (a - b \cos \theta)^2 d\phi^2 + b^2 d\theta^2 \quad (13)$$

$$\Rightarrow \left(\frac{ds}{d\phi} \right)^2 = (a - b \cos \theta)^2 + b^2 \left(\frac{d\theta}{d\phi} \right)^2 \quad (14)$$

$$\Rightarrow b^2 \left(\frac{d\theta}{d\phi} \right)^2 = \left(\frac{d\phi}{ds} \right)^{-2} - (a - b \cos \theta)^2 \quad (15)$$

$$(12) : b^2 \left(\frac{d\theta}{d\phi} \right)^2 = \frac{(a - b \cos \theta)^4}{h^2} - (a - b \cos \theta)^2 \quad (16)$$



5.25 p186 - Exercise 6

Consider the motion of a particle under gravity on the smooth torus of the previous problem, the equatorial plane of the torus being horizontal. Taking the mass of the particle to unity, so that $V = bg \sin \theta$, show that the path of the particle satisfies the following two differential equations.

$$(a) \quad (E - V)(a - b \cos \theta)^2 \frac{d\phi}{ds} = h$$

$$(b) \quad b^2 \left(\frac{d\theta}{d\phi} \right)^2 = (E - V) \frac{(a - b \cos \theta)^4}{h^2} - (a - b \cos \theta)^2$$

where E is the total energy, h is a constant and $d\sigma$ is the action line element.

The line of reasoning is quite the same as problem (5). We use equation 5.212. and 5.212.

$$\left\{ \begin{array}{l} \frac{d}{dt} \frac{\partial T}{\partial \dot{x}^s} - \frac{\partial T}{\partial x^s} = F_s \\ T = \frac{1}{2} m a_{pq} \dot{x}^p \dot{x}^q, \quad \dot{x}^s = \frac{dx^s}{dt} \end{array} \right. \quad (1)$$

with for our case

$$T = \frac{1}{2} m \left(b^2 \dot{\theta}^2 + (a - b \cos \theta)^2 \dot{\phi}^2 \right) \quad (2)$$

$$\left\{ \begin{array}{ll} \frac{\partial T}{\partial \dot{\phi}} = m(a - b \cos \theta)^2 \dot{\phi} & \frac{\partial T}{\partial \phi} = 0 \\ \frac{\partial T}{\partial \dot{\theta}} = mb^2 \dot{\theta} & \frac{\partial T}{\partial \theta} = mb(a - b \cos \theta) \dot{\phi}^2 \sin \theta \end{array} \right. \quad (3)$$

giving (as $F_\phi = -\partial_\phi V = 0$ and $F_\theta = -\partial_\theta V = -bg \cos \theta$)

$$\left\{ \begin{array}{l} (a - b \cos \theta)^2 \ddot{\phi} + 2b(a - b \cos \theta) \dot{\theta} \dot{\phi} \sin \theta = 0 \\ b^2 \ddot{\theta} - b(a - b \cos \theta) \dot{\phi}^2 \sin \theta = -bg \cos \theta \end{array} \right. \quad (4)$$

$$\Rightarrow \left\{ \begin{array}{l} (a - b \cos \theta) \ddot{\phi} = -2b \dot{\theta} \dot{\phi} \sin \theta \\ b^2 \ddot{\theta} - b(a - b \cos \theta) \dot{\phi}^2 \sin \theta = -bg \cos \theta \end{array} \right. \quad (5)$$

In the first equation, put $y \equiv \dot{\phi}$ giving for the first equation:

$$\frac{dy}{y} = -2b \frac{\sin \theta d\theta}{(a - b \cos \theta)} \quad (6)$$

$$\Leftrightarrow \frac{dy}{y} = -2 \frac{d(a - b \cos \theta)}{(a - b \cos \theta)} \quad (7)$$

$$\Rightarrow \log y = -2 \log(a - b \cos \theta) + \log C \quad (8)$$

$$\Rightarrow \dot{\phi} = C (a - b \cos \theta)^{-2} \quad (9)$$

Note that $\dot{\phi}$ is a time derivative. Using $\frac{ds}{dt} = v = \sqrt{2T} = \sqrt{2\sqrt{E-V}}$, (9) can be written as

$$(a - b \cos \theta)^2 \frac{d\phi}{dt} = C \quad (10)$$

$$\Leftrightarrow (a - b \cos \theta)^2 \frac{d\phi}{d\sigma} \underbrace{\frac{d\sigma}{ds}}_{=\sqrt{E-V}} \underbrace{\frac{ds}{dt}}_{=\sqrt{2}\sqrt{E-V}} = C \quad (11)$$

$$\Leftrightarrow (E - V) (a - b \cos \theta)^2 \frac{d\phi}{d\sigma} = h \quad (12)$$

with $h = \frac{C}{\sqrt{2}}$.

Next, we don't use the second equation in (5) but the line element equation instead

$$ds^2 = (a - b \cos \theta)^2 d\phi^2 + b^2 d\theta^2 \quad (13)$$

$$\Rightarrow \left(\frac{ds}{d\phi} \right)^2 = (a - b \cos \theta)^2 + b^2 \left(\frac{d\theta}{d\phi} \right)^2 \quad (14)$$

$$\Rightarrow b^2 \left(\frac{d\theta}{d\phi} \right)^2 = \left(\frac{d\phi}{ds} \right)^{-2} - (a - b \cos \theta)^2 \quad (15)$$

$$\Leftrightarrow b^2 \left(\frac{d\theta}{d\phi} \right)^2 = \left(\frac{d\phi}{d\sigma} \right)^{-2} \left(\frac{d\sigma}{ds} \right)^{-2} - (a - b \cos \theta)^2 \quad (16)$$

$$(12) \quad : \quad b^2 \left(\frac{d\theta}{d\phi} \right)^2 = (E - V)^2 \frac{1}{(E - V)} \frac{(a - b \cos \theta)^4}{h^2} - (a - b \cos \theta)^2 \quad (17)$$

$$\Rightarrow b^2 \left(\frac{d\theta}{d\phi} \right)^2 = (E - V) \frac{(a - b \cos \theta)^4}{h^2} - (a - b \cos \theta)^2 \quad (18)$$

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5.26 p187 - Exercise 7

A dynamical system consists of a thin straight smooth tube which can rotate in a horizontal plan about one end O , together with a bead B inside the tube connected to O by a spring. Taking as coordinates $r = OB$ and $\theta =$ angle of rotation of the tube about O , the potential energy V is a function of r only. Show that in configuration space, all the lines of force are geodesics for the kinematical line element.

Well understanding the question is of course paramount:

- The tube mentioned plays only a functional role to hold the spring "stiff" along the line OB as its mass can be neglected. It will play no further role in the dynamics of the system.
- Nothing is said that the system contains any force that keeps the angular velocity at a constant speed ω .

That being clarified, one can expect that the system will behave as a harmonic oscillator along the line OB and that, given an initial rotational momentum, the angular momentum will be a constant during the trajectory of the bead. This means that the bead will oscillate along OB but as the angular momentum is a constant and given $m\omega r^2 = C$ ($m =$ mass of the bead), the instant radial speed will vary.

The only conservative force acting on the bead will be that of the spring and will be $V = \frac{1}{2}k(r - r_0)^2$, r_0 being the point along OB where the spring is not stretched. The generalized forces are $F_r = -k(r - r_0)$ and $F_\theta = 0$ meaning the lines of force are straight lines pointing to the origin O .

About the geodesics. Clearly the instantaneous velocity of the bead is $\vec{v} = \dot{r}\vec{1}_r + \dot{\theta}r\vec{1}_\theta$ giving as kinetic energy $T = \frac{1}{2}(\dot{r}^2 + \dot{\theta}^2 r^2)$ giving as kinematic line element

$$ds^2 = 2Tdt = dr^2 + r^2 d\theta^2$$

Referring to **3.101**, the configuration space is flat and the geodesics are straight lines. As the line forces are straight lines towards the origin O , these line of force are also geodesics in the configuration space equipped with the kinematical line element.



5.27 p187 - Exercise 8

Show that if a line of force is a geodesic for the kinematical line element, it is also a geodesic for the action line element.

From 5.516 and 5.529 we have

$$X^r = v \frac{dv}{ds} \lambda^r + \kappa v^2 \nu^r \quad (1)$$

As the line of force is a geodesic, we can start with a velocity tangent to the line of force, ensuring that the trajectory of the dynamical system will lie on the geodesic line of force (see page 175) and thus $\kappa = 0$ for the trajectory. Hence,

$$X^r = v \frac{dv}{ds} \lambda^r \quad (2)$$

expressing now the function of the action line element $d\sigma = \sqrt{E - V} ds$ we have

$$X^r = v \frac{dv}{ds} \lambda^r \quad (3)$$

$$= v \frac{dv}{ds} \frac{dx^r}{d\sigma} \frac{d\sigma}{ds} \quad (4)$$

$$= v \frac{dv}{ds} \frac{dx^r}{d\sigma} \sqrt{E - V} \quad (5)$$

$$= \sqrt{E - V} v \frac{dv}{ds} \lambda'^r \quad (6)$$

As stated page 177, this dynamical system will describe in configuration space a geodesic for the action metric, meaning that λ'^r is tangent to this geodesic and that X^r , being collinear with λ'^r (with the factor $\sqrt{E - V} v \frac{dv}{ds}$), is also tangent to this geodesic. Hence, this line of force is also a geodesic for the action line element.



5.28 p187 - Exercise 9

Using the methods of Chapter II and **5.532**, show that the trajectories of a dynamical system with kinetic energy T and potential energy V satisfy the variational equation

$$\delta \int_{t_1}^{t_2} (T - V) dt = 0$$

Let's start with a function L defined by

$$dL = (T - V)du \quad (1)$$

$$(2)$$

As in figure 2 page 38 we will make L a function of two parameters, u and v , the latter defining a family of curves between the begin point u_1 and the endpoint u_2 .

$$L = L(u, v) \quad (3)$$

with

$$(T - V)(u_1, v) = (T - V)_1 \quad (T - V)(u_2, v) = (T - V)_2 \quad \forall v \quad (4)$$

We will try to minimize (with respect to v) the following functional

$$L = \int_{u_1}^{u_2} (T - V)(u, v) du \quad (5)$$

It's derivative with respect to v

$$\frac{dL}{dv} = \int_{u_1}^{u_2} \frac{\partial(T - V)(u, v)}{\partial v} du \quad (6)$$

We express $(T - V)(u, v)$ as a function of the generalized coordinates x^r and their derivatives. Then,

$$\frac{\partial(T - V)(u, v)}{\partial v} = \frac{\partial(T - V)(u, v)}{\partial \dot{x}^r} \frac{\partial \dot{x}^r}{\partial v} + \frac{\partial(T - V)(u, v)}{\partial x^r} \frac{\partial x^r}{\partial v} \quad (7)$$

where $\dot{x}^r = \frac{\partial x^r}{\partial u}$.

We have

$$\frac{\partial \dot{x}^r}{\partial v} = \frac{\partial}{\partial v} \frac{\partial x^r}{\partial u} = \frac{\partial}{\partial u} \frac{\partial x^r}{\partial v} \quad (8)$$

So,

$$\frac{\partial(T - V)(u, v)}{\partial v} = \frac{\partial(T - V)(u, v)}{\partial \dot{x}^r} \frac{\partial}{\partial u} \frac{\partial x^r}{\partial v} + \frac{\partial(T - V)(u, v)}{\partial x^r} \frac{\partial x^r}{\partial v} \quad (9)$$

Consider the expression

$$\int_{u_1}^{u_2} d(AB) = \int_{u_1}^{u_2} Ad(B) + \int_{u_1}^{u_2} Bd(A) \quad (10)$$

$$\Rightarrow \int_{u_1}^{u_2} Ad(B) = \int_{u_1}^{u_2} d(AB) - \int_{u_1}^{u_2} Bd(A) \quad (11)$$

Put $B = \frac{\partial x^r}{\partial v}$ and $A = \frac{\partial(T-V)(u,v)}{\partial x^r}$ and putting this inside (9) and (6):

$$\frac{dL}{dv} = \int_{u_1}^{u_2} d\left(\frac{\partial(T-V)(u,v)}{\partial x^r} \frac{\partial x^r}{\partial v}\right) - \int_{u_1}^{u_2} \frac{\partial x^r}{\partial v} d\left(\frac{\partial(T-V)(u,v)}{\partial x^r}\right) + \int_{u_1}^{u_2} \frac{\partial(T-V)(u,v)}{\partial x^r} \frac{\partial x^r}{\partial v} du \quad (12)$$

$$= \frac{\partial(T-V)(u,v)}{\partial x^r} \frac{\partial x^r}{\partial v} \Big|_{u_1}^{u_2} - \left[\int_{u_1}^{u_2} \left(\frac{\partial}{\partial u} \left(\frac{\partial(T-V)(u,v)}{\partial x^r} \right) - \frac{\partial(T-V)(u,v)}{\partial x^r} \right) \frac{\partial x^r}{\partial v} du \right] \quad (13)$$

We express now the results in term of infinitesimals. A change in "length" δL when we pas from a curve v to a curve $v + dv$ is

$$\delta L = \frac{dL}{dv} \delta v \quad (14)$$

$$= \frac{\partial(T-V)(u,v)}{\partial x^r} \frac{\partial x^r}{\partial v} \delta v \Big|_{u_1}^{u_2} - \int_{u_1}^{u_2} \left(\frac{\partial}{\partial u} \left(\frac{\partial(T-V)(u,v)}{\partial x^r} \right) - \frac{\partial(T-V)(u,v)}{\partial x^r} \right) \frac{\partial x^r}{\partial v} \delta v du \quad (15)$$

$$= \frac{\partial(T-V)(u,v)}{\partial x^r} \delta x^r \Big|_{u_1}^{u_2} - \int_{u_1}^{u_2} \left(\frac{\partial}{\partial u} \left(\frac{\partial(T-V)(u,v)}{\partial x^r} \right) - \frac{\partial(T-V)(u,v)}{\partial x^r} \right) \delta x^r du \quad (16)$$

The first term vanish as at the endpoints the δx^r are zero and hence we get

$$\delta L = - \int_{u_1}^{u_2} \left(\frac{\partial}{\partial u} \left(\frac{\partial(T-V)(u,v)}{\partial x^r} \right) - \frac{\partial(T-V)(u,v)}{\partial x^r} \right) \delta x^r du \quad (17)$$

As the δx^r are arbitrary, we must have for $\delta L = 0$

$$\frac{\partial}{\partial u} \left(\frac{\partial(T-V)(u)}{\partial x^r} \right) - \frac{\partial(T-V)(u)}{\partial x^r} = 0 \quad (18)$$

This is the same equation as **5.532** which describe the motion of a system with a conservative force.



5.29 p188 - Exercise 10

Using the definition **5.5335** for I_{rs} , prove that if X_r is any non-zero vector, then $I_{rs}X_rX_s \geq 0$, and that the equality occurs only if all particles of the system are distributed on a single line.

By **5.335**

$$I_{rs} = \delta_{rs} \sum m z_q z_q - \sum m z_r z_s \quad (1)$$

Multiplying by $X_r X_s$:

$$I_{rs}X_rX_s = \underbrace{X_rX_s\delta_{rs}}_{=X_rX_r} \sum m z_q z_q - \sum m \underbrace{z_rX_r}_{=|z|_{(m)}|X|\cos\theta_m} \underbrace{z_sX_s}_{=|z|_{(m)}|X|\cos\theta_m} \quad (2)$$

with θ_m the angle between the vector X_r and the position vector z_m of a particle.

$$I_{rs}X_rX_s = |X|^2 \sum m |z|_{(m)}^2 - |X|^2 \sum m |z|_{(m)}^2 \cos^2 \theta_m \quad (3)$$

$$= |X|^2 \sum m |z|_{(m)}^2 (1 - \cos^2 \theta_m) \quad (4)$$

As we have $(1 - \cos^2 \theta_m) \in [0, 1]$ it is clear that $I_{rs}X_rX_s \geq 0$ and that it only will be zero when $\theta_m = 0 \quad \forall m$ which means that all position vectors are collinear with X_r and are on a line.



5.30 p188 - Exercise 11

Let $Oz_1z_2z_3$ and $O'z'_1z'_2z'_3$ be two sets of Cartesian axes parallel to one another. Consider a mass distribution and let I_{rs}, I'_{rs} be its moment of inertia tensors calculated for these two axes in accordance with 5.335. Writing $I'_{rs} = I_{rs} + K_{rs}$, evaluate K_{rs} .

By 5.335

$$I_{rs} = \delta_{rs} \sum m z_q z_q - \sum m z_r z_s \quad (1)$$

As the axes of both coordinate systems are parallel, we can write

$$z'_q = z_q + b_q \quad (2)$$

which gives for (1):

$$I'_{rs} = \delta_{rs} \sum m (z_q + b_q) (z_q + b_q) - \sum m (z_r + b_r) (z_s + b_s) \quad (3)$$

$$= \begin{cases} \delta_{rs} \sum m z_q z_q - \sum m z_r z_s \\ + \delta_{rs} \sum m b_q z_q - \sum m b_r z_s \\ + \delta_{rs} \sum m b_q z_q - \sum m b_s z_r \\ + \delta_{rs} \sum m b_q b_q - \sum m b_r b_s \end{cases} \quad (4)$$

$$= \begin{cases} I_{rs} \\ + \delta_{rs} \sum m b_q z_q - \sum m b_r z_s \\ + \delta_{rs} \sum m b_q z_q - \sum m b_s z_r \\ + \delta_{rs} \sum m b_q b_q - \sum m b_r b_s \end{cases} \quad (5)$$

$$(6)$$

The last term $\delta_{rs} \sum m b_q b_q - \sum m b_r b_s$ can be interpreted as a moment of inertia tensor for a single virtual mass $M = \sum m$ situated at the point b_q seen from the axes $Oz_1z_2z_3$. Let's denote it with $\tilde{I}_{rs} = \sum m (\delta_{rs} b_q b_q - b_r b_s)$.

The other two terms can also be seen as a rigid body of particles distributed in a plane perpendicular to one of the axis i.e. all particles are transported perpendicularly to a plane. We note that $\delta_{rs} \sum m b_q z_q - \sum m b_r z_s = \delta_{rs} \sum m b_q z_q - \sum m b_s z_r$. This follows immediately from the symmetric character of $I'_{rs}, I_{rs}, \tilde{I}_{rs}$.

Denoting $\bar{I}_{rs} = \delta_{rs} \sum m b_q z_q - \sum m b_r z_s + \delta_{rs} \sum m b_q z_q - \sum m b_s z_r$ giving

$$K_{rs} = I_{rs} + \bar{I}_{rs} + \tilde{I}_{rs}$$



5.31 p188 - Exercise 12

A rigid body is turning about a fixed point. Referred to right-handed axes $Oz_1z_2z_3$, its angular velocity tensor has components

$$\omega_{23} = 1, \quad \omega_{31} = 2, \quad \omega_{12} = 3$$

If we refer the same motion to the axis $O'z'_1z'_2z'_3$, such that the axis $O'z'_1$ is Oz'_1 reversed, while z_2z_3 coincide with $O'z'_2z'_3$, what are the ω'_{rs} and ω'_{rs} ?

We use the following identities

$$\left\{ \begin{array}{ll} \text{5.312} & \omega_{rm} = -\omega_{mr} \\ \text{5.316} & \omega_{rs} = \epsilon_{rsn}\omega_n \\ \text{5.317} & \omega_1 = \omega_{23} \quad \omega_2 = \omega_{31} \quad \omega_3 = \omega_{12} \end{array} \right. \quad (1)$$

The angular velocity tensor is

$$\Omega = \begin{pmatrix} 0 & 3 & -2 \\ -3 & 0 & 1 \\ 2 & -1 & 0 \end{pmatrix} \quad (2)$$

giving by **5.317**

$$\omega_1 = \omega_{23} \quad \omega_2 = \omega_{31} \quad \omega_3 = \omega_{12} \quad (3)$$

From pure geometrical consideration we can conclude that

$$\omega'_1 = -\omega_1 \quad \omega'_2 = \omega_2 \quad \omega'_3 = \omega_3 \quad (4)$$

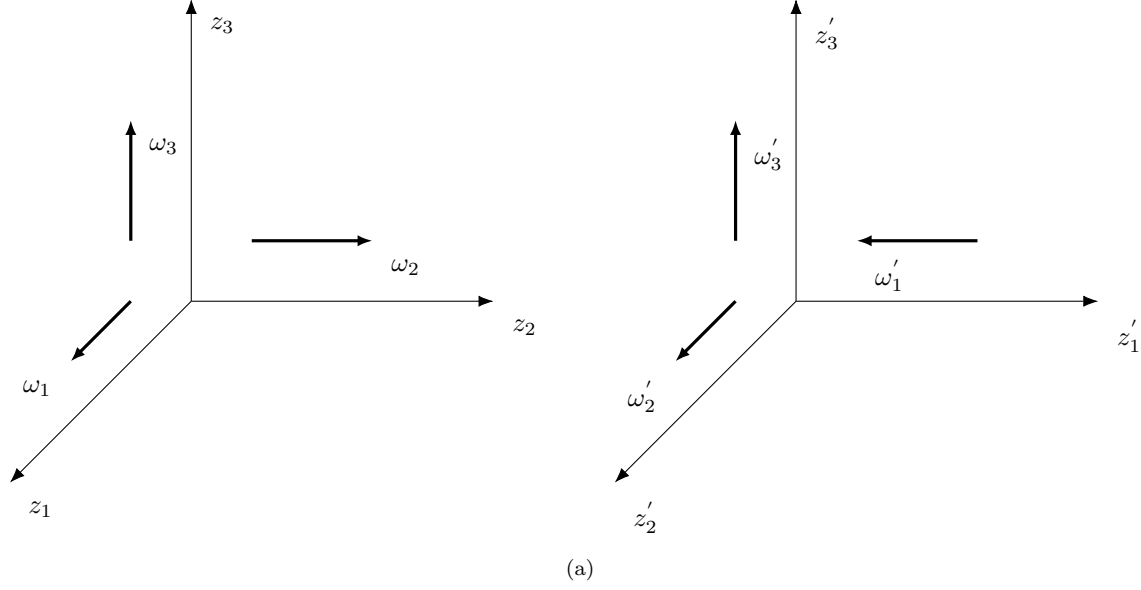


Figure 5.7: Angular velocity vectors in mirrored axis

Indeed, the ω_i can be considered as vectors, objects independent from the chosen coordinate system. Reversing the direction of the first axis, will for the observer looking along the positive direction, look as if the ω_1 is reversed. We now use $\omega_{rs} = \epsilon_{rsn}\omega_n$ but here we have to be careful with ϵ_{rsn} when using the equation in the transformed coordinate system.

Looking at **4.312** $\epsilon'_{stu} = \epsilon_{mnr} \frac{\partial z_m}{\partial z'_s} \frac{\partial z_n}{\partial z'_t} \frac{\partial z_r}{\partial z'_u}$ and noting that $\frac{\partial z_1}{\partial z'_1} = -1$ and 1 or 0 for the others, we have $\epsilon'_{stu} = -\epsilon_{mnr}$. Now with **5.316** we get

$$\omega'_{rs} = -\epsilon_{rsn}\omega'_n \quad (5)$$

giving

$$\omega'_{12} = -\omega_{12} \quad \omega'_{13} = -\omega_{13} \quad \omega'_{23} = \omega_{23} \quad (6)$$

Giving

$$\Omega' = \begin{pmatrix} 0 & -3 & 2 \\ 3 & 0 & 1 \\ -2 & -1 & 0 \end{pmatrix} \quad (7)$$



5.32 p188 - Exercise 13

Consider three rigid bodies, S, S', S'' , turning about a common point. If all angular velocities are referred to common axes, show that the angular velocity tensors of S'' relative to S is the sum of the angular velocity tensors of S' relative to S and of S'' relative to S' .

Consider the following three transformation from one axes system to another

$$\begin{cases} z'_r = A_{rm} z_m & z_r = A_{mr} z'_m & A_{mp} A_{mq} = \delta_{pq} & A_{pm} A_{qm} = \delta_{pq} \\ z''_r = B_{rm} z'_m & z'_r = B_{mr} z''_m & B_{mp} B_{mq} = \delta_{pq} & B_{pm} B_{qm} = \delta_{pq} \\ z''_r = C_{rm} z_m & z_r = C_{mr} z''_m & C_{mp} C_{mq} = \delta_{pq} & C_{pm} C_{qm} = \delta_{pq} \end{cases} \quad (1)$$

We then have,

$$\begin{cases} \omega'_{pq}(S', S) = -A_{pm} \dot{A}_{qm} \\ \omega''_{pq}(S'', S') = -B_{pm} \dot{B}_{qm} \\ \omega''_{pq}(S'', S) = -C_{pm} \dot{C}_{qm} \end{cases} \quad (2)$$

From (1) we see that

$$C_{rq} = B_{rm} A_{mq} \quad (3)$$

And thus

$$\omega''_{pq}(S'', S) = -B_{pk} A_{km} (B_{qn} \dot{A}_{nm}) \quad (4)$$

$$\Rightarrow \quad = \underbrace{-A_{km} \dot{A}_{nm}}_{=\omega'_{kn}(S', S)} B_{pk} B_{qn} - \underbrace{A_{km} A_{nm}}_{=\delta_{kn}} B_{pk} \dot{B}_{qn} \quad (5)$$

$$\Rightarrow \quad = \omega'_{kn}(S', S) B_{pk} B_{qn} - \underbrace{B_{pn} \dot{B}_{qn}}_{=-\omega''_{pq}(S'', S')} \quad (6)$$

The first term of the right side expression is a bilinear map of the tensor $\omega'_{kn}(S', S)$ from the reference axis S' to S'' . Hence we get

$$\omega''_{pq}(S'', S) = \omega''_{pq}(S'', S') + \omega''_{pq}(S', S) \quad (7)$$



5.33 p188 - Exercise 14

A freely moving particle is observed from a platform which rotates with angular velocity $\omega_r = n\delta_{r3}$, where n is constant, relative to a Newtonian frame S in which z_r are rectangular Cartesians. Use **5.421** to find the equations of motion relative to S' in terms of coordinates z'_r in S' , such that the axis of z'_3 coincides permanently with the axis of z_3 .

5.421 gives (where the equation is expressed in term of the z'_r

$$\begin{cases} mf_s = F'_s + C'_s + G'_s \\ C'_s = m \left[\dot{\omega}'_{sn} (S', S) + \omega'_{sm} (S', S) \omega'_{nm} (S', S) \right] z'_n \\ C'_s = 2m\omega'_{sm} v'_m (S') \end{cases} \quad (1)$$

We note the particle is free, so $F'_s = 0$ and the angular velocity is a constant, so $\dot{\omega}'_{sn} (S', S) = 0$, and the equation simplify to

$$\begin{cases} f'_s = K'_s + J'_s \\ K'_s = \left[\omega'_{sm} (S', S) \omega'_{nm} (S', S) \right] z'_n \\ J'_s = 2\omega'_{sm} v'_m (S') \end{cases} \quad (2)$$

As $\omega_s = n\delta_{s3}$ and by the requirement that the axis of z'_3 coincides permanently with the axis of z_3 , it is not hard to see that

$$\begin{cases} \omega_{12} (S', S) = n \\ \omega'_{12} (S', S) = n \\ \omega_{12} (S, S') = -n \\ \omega'_{12} (S, S') = -n \end{cases} \quad (3)$$

while all other elements vanish.

We get

$$\begin{cases} K'_1 = \omega'_{12} (S', S) \omega'_{12} (S', S) z'_1 = n^2 z'_1 \\ K'_1 = \omega'_{21} (S', S) \omega'_{21} (S', S) z'_1 = n^2 z'_1 \\ K'_3 = 0 \end{cases} \quad (4)$$

$$\begin{cases} J'_1 = 2\omega'_{12} (S', S) v'_2 (S') = 2nv'_2 (S') \\ J'_2 = 2\omega'_{21} (S', S) v'_1 (S') = -2nv'_1 (S') \\ J'_3 = 0 \end{cases} \quad (5)$$

and get as equations of motion

$$\begin{cases} f_1' = n^2 z_1' + 2nv_2' \left(S' \right) \\ f_2' = n^2 z_1' - 2nv_1' \left(S' \right) \\ f_3' = 0 \end{cases} \quad (6)$$



5.34 p188 - Exercise 15

If the tensor I_{st} is defined by **5.335** for N dimensions, and J_{nprq} is defined by **5.330**, establish the following relations:

$$J_{nprq} = (N - 1)^{-1} I_{ss} (\delta_{nr} \delta_{pq} - \delta_{nq} \delta_{pr}) - \delta_{nr} I_{pq} + \delta_{pr} I_{nq}$$

$$J_{nppq} = I_{ss}$$

$$I_{nq} = (N - 1)^{-1} (J_{nprq} - \delta_{nq} J_{nprq})$$

5.421 and **5.421**:

$$\begin{cases} I_{st} = \delta_{st} \sum m z_q z_q - \sum m z_s z_t \\ J_{nprq} = \sum m (\delta_{nr} z_p z_q - \delta_{pr} z_n z_q) \end{cases} \quad (1)$$

The first equation can be expressed as $\sum m z_p z_q = \delta_{pq} \sum m z_k z_k - I_{pq}$ and $\sum m z_n z_q = \delta_{st} \sum m z_k z_k - I_{nq}$ giving

$$J_{nprq} = \delta_{nr} \delta_{pq} \sum m z_k z_k - \delta_{nr} I_{pq} - \delta_{pr} \delta_{st} \sum m z_k z_k + \delta_{pr} I_{nq} \quad (2)$$

$$= \sum m z_k z_k (\delta_{nr} \delta_{pq} - \delta_{nr} I_{pq}) - \delta_{nr} I_{pq} + \delta_{pr} I_{nq} \quad (3)$$

Now, consider the expressions

$$\begin{cases} I_{11} = \sum m z_q z_q - \sum m z_1 z_1 \\ I_{11} = \sum m z_q z_q - \sum m z_1 z_1 \\ \vdots \\ I_{NN} = \sum m z_q z_q - \sum m z_N z_N \end{cases} \quad (4)$$

Summing up these N expressions we have

$$I_{ss} = N \left(\sum m z_q z_q \right) - \sum m z_q z_q \quad (5)$$

$$= (N - 1) \sum m z_q z_q \quad (6)$$

$$\Rightarrow \sum m z_q z_q = I_{ss} (N - 1)^{-1} \quad (7)$$

Plugging this in (3) we get

$$J_{nprq} = I_{ss} (N - 1)^{-1} (\delta_{nr} \delta_{pq} - \delta_{nr} I_{pq}) - \delta_{nr} I_{pq} + \delta_{pr} I_{nq} \quad (8)$$



5.35 p188 - Exercise 16 †

The motion of a dynamical system is represented by a curve in configuration-space. Using the kinematical line element, express the curvature as a function of its total energy E , and deduce that as E tends to infinity, the trajectory tends to become a geodesic. Illustrate by considering a particle moving under gravity on a smooth sphere.

We have **5.512** and **5.533**:

$$\begin{cases} v^2 = a_{mn}v^mv^n = 2T \\ \kappa v^2 = X_r\nu^r \end{cases} \Rightarrow \kappa = \frac{X_r\nu^r}{2T} \quad (1)$$

First, we have to note that nothing is said about the nature of the generalized forces (conservative or not) and therefore we use **5.517**

$$dW = X_r dx^r \quad (2)$$

From this we can express T as

$$T(s) = T_0 + \int_0^s dW \quad (3)$$

$$= T_0 + \int_0^s X_r dx^r \quad (4)$$

where T_0 is the kinetic energy at the initial configuration $s = 0$.

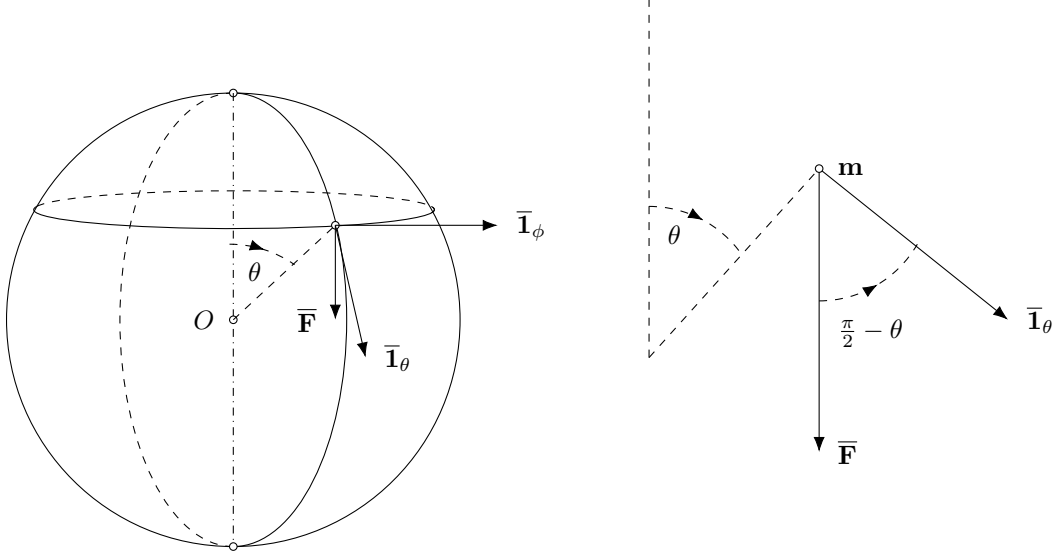
†

Suppose now that for $s \rightarrow +\infty$, $\int_0^s dW \rightarrow +\infty$. In that case, the kinematical energy will represent the total energy of the system, $T \rightarrow E$ and $\kappa \rightarrow 0$ for $E \rightarrow +\infty$ provided that $X_r\nu^r \not\rightarrow \pm\infty$ which we will assume.

†

◇

Let's illustrate this with a particle on a smooth sphere moving under gravity.

Figure 5.8: Physical components of the gravitational force tensor acting on a mass \mathbf{m} on a sphere**INTERMEZZO:**

The next calculation are showed how careful we have to be when applying blindly some formulas. The aim is to find the equation of motion in the configuration space equipped with the kinematical fundamental form, starting from the physical components of the force field.

We have as physical components:

$$\begin{cases} F_\phi^{phys} = 0 \\ F_\theta^{phys} = mg \sin \theta \end{cases} \quad (5)$$

Using **5.109** and **5.110** combined with the kinematical fundamental form, $ds^2 = 2Tdt^2 = (\sqrt{m}R)^2 d\theta^2 + (\sqrt{m}R \sin \theta)^2 d\phi^2$

$$(a_{mn}) = \begin{pmatrix} mR^2 & 0 \\ 0 & mR^2 \sin^2 \theta \end{pmatrix} \quad (6)$$

$$\begin{cases} h_1 = \sqrt{m}R & [M]^{\frac{1}{2}}[L] \\ h_2 = \sqrt{m}R \sin \theta & [M]^{\frac{1}{2}}[L] \\ F_\phi^{phys} = 0 & [M][L][T]^{-2} \\ F_\theta^{phys} = mg \sin \theta & [M][L][T]^{-2} \\ v_\phi^{phys} = R \sin \theta \dot{\phi} & [L][T]^{-1} \\ v_\theta^{phys} = R \dot{\theta} & [L][T]^{-1} \end{cases} \quad (7)$$

we have

$$\left\{ \begin{array}{ll} X^\phi = 0 & X_\phi = 0 \\ X_\theta = F_\theta^{phys} h_1 = m^{\frac{3}{2}} g R \sin \theta & [M]^{\frac{3}{2}} [L]^2 [T]^{-2} \\ X^\theta = \frac{F_\theta^{phys}}{h_1} = \frac{m g \sin \theta}{\sqrt{m} R} = \frac{\sqrt{m} g \sin \theta}{R} & [M]^{\frac{1}{2}} [T]^{-2} \\ v_\theta = v_\theta^{phys} h_1 = \sqrt{m} R^2 \dot{\theta} & [M]^{\frac{1}{2}} [L]^2 [T]^{-1} \\ v^\theta = \frac{v_\theta^{phys}}{h_1} = \frac{R \dot{\theta}}{\sqrt{m} R} = \frac{1}{\sqrt{m}} \dot{\theta} & [M]^{-\frac{1}{2}} [T]^{-1} \\ v_\phi = v_\phi^{phys} h_1 = \sqrt{m} R^2 \sin \theta \dot{\phi} & [M]^{\frac{1}{2}} [L]^2 [T]^{-1} \\ v^\phi = \frac{v_\phi^{phys}}{h_1} = \frac{R \sin \theta \dot{\phi}}{\sqrt{m} R} = \frac{1}{\sqrt{m}} \dot{\phi} & [M]^{-\frac{1}{2}} [T]^{-1} \end{array} \right. \quad (8)$$

Check 1:

$$X_\theta = a_{11} X^\theta \quad (9)$$

$$= m R^2 \frac{\sqrt{m} g \sin \theta}{R} \quad (10)$$

$$= m^{\frac{3}{2}} g R \sin \theta \quad (11)$$

Check 2:

$$v_\theta = a_{11} v^\theta + a_{12} v^\phi \quad (12)$$

$$= m R^2 \frac{1}{\sqrt{m}} \dot{\theta} \quad (13)$$

$$= \sqrt{m} R^2 \dot{\theta} \quad (14)$$

Check 3:

$$\underbrace{f^\theta = X^\theta}_{\sim [M]^{\frac{1}{2}} [T]^{-2}} = \underbrace{\frac{\delta v^\theta}{\delta t}}_{\sim [M]^{-\frac{1}{2}} [T]^{-2}} \quad (15)$$

$$[M]^{\frac{1}{2}} [T]^{-2} \neq [M]^{-\frac{1}{2}} [T]^{-2} \quad (16)$$

So, obviously, we ran into a problem.

The reason is due to the fact that the physical components and the generalized coordinates are not equipped with the same metric. Indeed, consider a system with only one mass. Then there is no fundamental difference in the geometry of the two spaces ('physical' and 'generalized coordinates space') but, if ds is a distance in the physical space and ds' a distance in the 'generalized coordinates space' (abuse of language), then $ds' \neq ds$ as $ds' = \sqrt{m} ds$. So, the same physical object will be 'seen'

stretched by a factor \sqrt{m} when observed in the generalized configuration space. So let's begin again but with adapted conversion factors h_i .

$$\left\{ \begin{array}{ll} h_1 = R & [M]^{\frac{1}{2}}[L] \\ h_2 = R \sin \theta & [M]^{\frac{1}{2}}[L] \\ F_\phi^{phys} = 0 & [M][L][T]^{-2} \\ F_\theta^{phys} = mg \sin \theta & [M][L][T]^{-2} \\ v_\phi^{phys} = R \sin \theta \dot{\phi} & [L][T]^{-1} \\ v_\theta^{phys} = R \dot{\theta} & [L][T]^{-1} \end{array} \right. \quad (17)$$

we have

$$\left\{ \begin{array}{ll} X^\phi = 0 & X_\phi = 0 \\ X_\theta = F_\theta^{phys} h_1 = mgR \sin \theta & [M][L]^2[T]^{-2} \\ X^\theta = \frac{F_\theta^{phys}}{h_1} = \frac{mg \sin \theta}{R} = \frac{mg \sin \theta}{R} & [M][T]^{-2} \\ v_\theta = v_\theta^{phys} h_1 = R^2 \dot{\theta} & [L]^2[T]^{-1} \\ v^\theta = \frac{v_\theta^{phys}}{h_1} = \frac{R \dot{\theta}}{R} = \dot{\theta} & [T]^{-1} \\ v_\phi = v_\phi^{phys} h_2 = R^2 \sin^2 \theta \dot{\phi} & [L]^2[T]^{-1} \\ v^\phi = \frac{v_\phi^{phys}}{h_2} = \frac{R \sin \theta \dot{\phi}}{R \sin \theta} = \dot{\phi} & [T]^{-1} \end{array} \right. \quad (18)$$

Check 1:

$$X_\theta = a_{11} X^\theta \quad (19)$$

$$= mR^2 \frac{mg \sin \theta}{R} \quad (20)$$

$$= m^2 g R \sin \theta \quad (21)$$

$$\neq mgR \sin \theta \quad (22)$$

Check 2:

$$v_\theta = a_{11} v^\theta + a_{12} v^\phi \quad (23)$$

$$= mR^2 \dot{\theta} \quad (24)$$

$$\neq R^2 \dot{\theta} \quad (25)$$

Check 3:

$$\underbrace{f^\theta = X^\theta}_{\sim [M][T]^{-2}} = \underbrace{\frac{\delta v^\theta}{\delta t}}_{\sim [T]^{-2}} \quad (26)$$

$$[M][T]^{-2} \neq [T]^{-2} \quad (27)$$

Again, we ran into problems.

In fact, the idea of going from the physical space into the configuration space, by some transformation rule is wrong because, in configuration space equipped with the kinematical fundamental form, velocity and generalized forces have their very own, specific definition:

$$\left\{ \begin{array}{ll} \text{velocity:} & v^r = \frac{dx^r}{dt} \\ \text{generalized forces:} & dW = X_r dx^r \end{array} \right. \quad (28)$$

and get for the velocities

$$v^\theta = \dot{\theta} \quad (29)$$

$$v^\phi = \dot{\phi} \quad (30)$$

and for the generalized forces

$$\left\{ \begin{array}{ll} dW = F_\theta^{phys} R d\theta & \text{in the physical space} \\ dW = X_\theta d\theta & \text{in the configuration space} \end{array} \right. \quad (31)$$

and by the invariance of dW we get

$$X_\theta = mgR \sin \theta \quad (32)$$

$$\Rightarrow X^\theta = a^{11} mgR \sin \theta \quad (33)$$

$$= \frac{mgR \sin \theta}{mR^2} \quad (34)$$

$$= \frac{g \sin \theta}{R} \quad (35)$$

and get for check 3:

$$\underbrace{f^\theta = X^\theta}_{\sim [T]^{-2}} = \underbrace{\frac{\delta v^\theta}{\delta t}}_{\sim [T]^{-2}} \quad (36)$$

$$[T]^{-2} = [T]^{-2} \quad (37)$$

and get what we wanted.

Let's go on with the equations of motion in the configuration space: assuming that the gravitational force is conservative, we get as potential energy:

$$V = -mgR \cos \theta \quad (38)$$

We use equation **5.531**.

$$\frac{d}{dt} \frac{\partial L}{\partial \dot{x}^s} - \frac{\partial L}{\partial x^s} = 0 \quad (39)$$

with for our case

$$L = \frac{1}{2}mR^2\dot{\theta}^2 + \frac{1}{2}mR^2 \sin^2 \theta \dot{\phi}^2 + mgR \cos \theta \quad (40)$$

and get the set of equations of motion (the second column gives the dimensional analysis as a check for consistency)

$$\left\{ \begin{array}{ll} \frac{\ddot{\phi}}{\dot{\phi}} = -2 \cot \theta \dot{\theta} & : \quad \frac{[T]^{-2}}{[T]^{-1}} \cong [T]^{-1} \\ \ddot{\theta} - \left(\dot{\phi}\right)^2 \sin \theta \cos \theta = -\frac{g}{R} \sin \theta & : \quad [T]^{-2} + ([T]^{-1})^2 \cong \frac{[L][T]^{-2}}{[L]} \end{array} \right. \quad (41)$$



5.36 p189 - Exercise 17

A particle moves on a smooth sphere under action of gravity. Using the action line element, calculate the Gaussian curvature of configuration-space as a function of total energy E and height z above the centre of the sphere. Show that if the total energy is not sufficient to raise the particle to the top of the sphere, but only to a level $z = h$, then the Gaussian curvature tends to infinity as z approaches h from below.

Using polar spherical coordinates, the line element on the sphere is

$$ds^2 = R^2 d\theta^2 + R^2 \sin^2 \theta d\phi^2 \quad (1)$$

For the potential energy, we use the lowest point (along the axis of the gravitational field) as reference. Hence the potential is given by

$$V = mgR + mgz \quad (2)$$

$$= R(1 + mg \cos \theta) \quad (3)$$

Giving for the action line element (with a total energy of the system E_0)

$$d\sigma^2 = (E_0 - mgR - mgR \cos \theta) ds^2 \quad (4)$$

Be $E = E_0 - mgR$

$$(a_{mn}) = \begin{pmatrix} R^2 (E - mgR \cos \theta) & 0 \\ 0 & R^2 (E - mgR \cos \theta) \sin^2 \theta \end{pmatrix} \quad (5)$$

3.114 and the exercise (Riemann curvature of a 2-space) on page 112 gives:

$$\begin{cases} G = \frac{R_{1212}}{a_{11}a_{22}} \\ R_{1212} = -\frac{1}{2}\partial_{11}^2 a_{22} - \frac{1}{4}a^{11}\partial_1 a_{11}\partial_1 a_{22} + \frac{1}{4}a^{22}\partial_1 a_{22}\partial_1 a_{22} \end{cases} \quad (6)$$

With

$$\left\{ \begin{array}{l} \partial_1 a_{11} = mgR^3 \sin \theta \\ \partial_1 a_{22} = 2ER^2 \sin \theta \cos \theta + R^3 mg (\sin^3 \theta - 2 \sin \theta \cos^2 \theta) \\ \partial_{11}^2 a_{22} = 2ER^2 (\cos^2 \theta - \sin^2 \theta) + R^3 mg (3 \cos \theta \sin^2 \theta - 2 (\cos^3 \theta - 2 \sin^2 \theta \cos \theta)) \\ \quad = 2ER^2 (\cos^2 \theta - \sin^2 \theta) + R^3 mg (7 \cos \theta \sin^2 \theta - 2 \cos^3 \theta) \\ a^{11} = \frac{1}{R^2 (E - mgR \cos \theta)} \\ a^{22} = \frac{1}{R^2 (E - mgR \cos \theta) \sin^2 \theta} \end{array} \right. \quad (7)$$

We first try now to replace the expressions in θ with expressions in $R \cos \theta = z$ and $R \sin \theta = \sqrt{R^2 - z^2}$

$$\left\{ \begin{array}{l} \partial_1 a_{11} = mgR^2 \sqrt{R^2 - z^2} \\ \partial_1 a_{22} = 2Ez \sqrt{R^2 - z^2} + mg ((R^2 - z^2) \sqrt{R^2 - z^2} - 2z^2 \sqrt{R^2 - z^2}) \\ \partial_{11}^2 a_{22} = 2E (2z^2 - R^2) + mg (7z (R^2 - z^2) - 2z^3) \\ a^{11} = \frac{1}{R^2 (E - mgz)} \\ a^{22} = \frac{1}{(E - mgz)(R^2 - z^2)} \end{array} \right. \quad (8)$$

$$\Rightarrow \left\{ \begin{array}{ll} \partial_1 a_{11} = mgR^2 \sqrt{R^2 - z^2} & ML^4 T^{-2} \\ \partial_1 a_{22} = (mgR^2 + 2Ez - 3mgz^2) \sqrt{R^2 - z^2} & ML^4 T^{-2} \\ \partial_{11}^2 a_{22} = 2E (2z^2 - R^2) + mgz (7R^2 - 9z^2) & ML^4 T^{-2} \\ a^{11} = \frac{1}{R^2 (E - mgz)} & M^{-1} L^{-4} T^2 \\ a^{22} = \frac{1}{(E - mgz)(R^2 - z^2)} & M^{-1} L^{-4} T^2 \\ a_{11} = R^2 (E - mgz) & ML^4 T^{-2} \\ a_{22} = (E - mgz) (R^2 - z^2) & ML^4 T^{-2} \end{array} \right. \quad (9)$$

giving

$$R_{1212} = -\frac{1}{2}\partial_{11}^2 a_{22} - \frac{1}{4}a^{11}\partial_1 a_{11}\partial_1 a_{22} + \frac{1}{4}a^{22}\partial_1 a_{22}\partial_1 a_{22} \quad (10)$$

$$= \begin{cases} -E(2z^2 - R^2) - \frac{1}{2}mgz(7R^2 - 9z^2) \\ -\frac{1}{4}\frac{1}{(E-mgz)}mg(R^2 - z^2)(mgR^2 + 2Ez - 3mgz^2) \\ +\frac{1}{4}\frac{1}{(E-mgz)}(mgR^2 + 2Ez - 3mgz^2)^2 \end{cases} \quad (11)$$

$$= \begin{cases} \frac{1}{4}\frac{1}{(E-mgz)}[(E-mgz)(-E(2z^2 - R^2) - \frac{1}{2}mgz(7R^2 - 9z^2)) \\ -mg(R^2 - z^2)(mgR^2 + 2Ez - 3mgz^2) \\ + (mgR^2 + 2Ez - 3mgz^2)^2] \end{cases} \quad (12)$$

$$= \frac{R^2 - z^2}{(E - mgz)} [3m^2 g^2 z^2 - 4Emgz + E^2] \quad (13)$$

$$= \frac{R^2 - z^2}{(E - mgz)} (E - mgz) [E - 3mgz] \quad (14)$$

$$= (R^2 - z^2) [E - 3mgz] \quad (15)$$

For the Gauss curvature we get then

$$G = \frac{R_{1212}}{R^2 (E - mgz)^2 (R^2 - z^2)} \quad (16)$$

and so

$$G = \frac{E - 3mgz}{R^2 (E - mgz)^2} \quad (17)$$

Be $h = \frac{E}{mg}$. From (17) we see that as long $z < \frac{h}{3}$, G is defined and positive. It becomes 0 for $z = \frac{h}{3}$ and negative for $z > \frac{h}{3}$ to become $-\infty$ for $z \rightarrow h$.

Remember that $E = E_0 - mgR$ with E_0 the total energy of the system and that the maximum potential energy is $V_{max} = 2mgR$. In order to reach the top, a particle starting from the bottom of the sphere ($V = 0$), should have at least a total energy $E_0 = 2mgR$.

Suppose now, that we configure the system so that the particle starts from the bottom and gets zero velocity at a point $z = h$. Then $E_0 = mg(R + h) < 2mgR$ and so $E = E_0 - mgR = mgh$.

(17) becomes

$$G = \frac{h - 3z}{mgR^2 (h - z)^2} \quad (18)$$

$$\Rightarrow \lim_{z \rightarrow h} G = -\infty \quad (19)$$



5.37 p189 - Exercise 18

Show that the equations of motion of a rigid body with a fixed point may be written in either of the forms

$$(a) \quad \dot{h}'_r + \omega'_{mr} \left(S', S \right) h'_m = M'_{rs},$$

$$(b) \quad \dot{h}'_r - K'_{rmn} h'_m h'_n = M'_{rs},$$

where h'_r are the components on z' -axes (moving with the body) of angular momentum as given in **5.338** and K'_{rmn} is a certain moment of inertia tensor. Evaluate the components K'_{rmn} in terms of the moments and products of inertia.

We use **5.329**, **5.231**, **5.233** and **5.424**:

$$M'_{rs} = \epsilon_{rsn} M'_n \quad (1)$$

$$h'_{rs} = \epsilon_{rsn} h'_n \quad (2)$$

$$h'_{np} = J'_{nprq} \omega'_{rq} \quad (3)$$

$$M'_{ab} = J'_{abrq} \dot{\omega}'_{rq} \left(S', S \right) + J'_{cdrq} (\delta_{ac} \delta_{du} \delta_{bv} + \delta_{bd} \delta_{cu} \delta_{av}) \omega'_{uv} \left(S', S \right) \omega'_{rq} \left(S', S \right) \quad (4)$$

Then, using (1), (2), (3) in (4) and contracting the terms in δ_{ij}

$$M'_{ab} = \dot{h}'_{ab} + h'_{au} \omega'_{ub} \left(S', S \right) + h'_{ub} \omega'_{ua} \left(S', S \right) \quad (5)$$

$$\Leftrightarrow \quad \epsilon_{abn} M'_n = \epsilon_{abn} \dot{h}'_n + \epsilon_{aun} h'_n \omega'_{ub} \left(S', S \right) + \epsilon_{ubn} h'_n \omega'_{ua} \left(S', S \right) \quad (6)$$

$$\times \epsilon_{abt} \Rightarrow \quad \epsilon_{abt} \epsilon_{abn} M'_n = \epsilon_{abt} \epsilon_{abn} \dot{h}'_n + \epsilon_{abt} \epsilon_{aun} h'_n \omega'_{ub} \left(S', S \right) + \epsilon_{bat} \epsilon_{bun} h'_n \omega'_{ua} \left(S', S \right) \quad (7)$$

$$\Rightarrow \quad 2M'_t = 2\dot{h}'_t + (\delta_{bu} \delta_{tn} - \delta_{bn} \delta_{tu}) h'_n \omega'_{ub} \left(S', S \right) + (\delta_{au} \delta_{tn} - \delta_{an} \delta_{tu}) h'_n \omega'_{ua} \left(S', S \right) \quad (8)$$

$$= 2\dot{h}'_t + h'_t \omega'_{bb} \left(S', S \right) - h'_b \omega'_{tb} \left(S', S \right) + h'_t \omega'_{uu} \left(S', S \right) - h'_a \omega'_{ta} \left(S', S \right) \quad (9)$$

And so,

$$M'_r = \dot{h}'_r + \omega'_{mr} \left(S', S \right) h'_m \quad (10)$$

◇

Let's try to express equation (4) but with the inertia tensor I_{ij} as parameter. We have **5.332**:

$$\frac{d \left(I_{st} \omega_t \left(S', S \right) \right)}{dt} = M_s \quad (11)$$

Let's express this in the coordinate system S' so that I'_{sr} will not depend of the time. Be A_{ij} the

map from S' to S . Then:

$$\frac{d \left(A_{ks} I'_{st} \omega'_t (S', S) \right)}{dt} = M_s \quad (12)$$

$$\times A_{ps} \quad A_{ps} \frac{d \left(A_{ks} I'_{st} \omega'_t (S', S) \right)}{dt} = M'_p \quad (13)$$

$$A_{ps} \dot{A}_{ks} I'_{kt} \omega'_t (S', S) + A_{ps} A_{ks} I'_{kt} \dot{\omega}'_t (S', S) = M'_p \quad (14)$$

We have

$$\begin{cases} \text{5.408} & \omega'_{ts} (S', S) = A_{tm} \dot{A}_{sm} \\ \text{5.401} & A_{mp} A_{mq} = \delta_{pq} \quad A_{pm} A_{qm} = \delta_{pq} \end{cases} \quad (15)$$

So, (14) becomes

$$\omega'_{pk} (S', S) I'_{kt} \omega'_t (S', S) + I'_{pt} \dot{\omega}'_t (S', S) = M'_p \quad (16)$$

We use

$$\omega'_{pk} (S', S) = \epsilon_{pkm} \omega'_m (S', S) \quad (17)$$

and get for (16):

$$I'_{pt} \dot{\omega}'_t (S', S) + \epsilon_{pkm} \omega'_m (S', S) I'_{kt} \omega'_t (S', S) = M'_p \quad (18)$$

Note also that $h'_s = I_{sr} \omega'_r (S', S)$. Indeed,

$$h'_{np} = J'_{npqr} \omega'_{rq} (S', S) \quad (19)$$

$$= J'_{npqr} \epsilon_{rqm} \omega'_m (S', S) \quad (20)$$

$$\times \frac{1}{2} \epsilon_{snp} \quad h'_s = \frac{1}{2} \underbrace{J'_{npqr} \epsilon_{snp} \epsilon_{rqm}}_{=I'_{sm}} \omega'_m (S', S) \quad (21)$$

$$\Rightarrow \quad h'_s = I'_{sm} \omega'_m (S', S) \quad (22)$$

and (18) becomes

$$\dot{h}'_p (S', S) + \epsilon_{pkm} I'_{kt} \omega'_m (S', S) \omega'_t (S', S) = M'_p \quad (23)$$

Let's examine the term $\epsilon_{pkm} I'_{kt} \omega'_m (S', S) \omega'_t (S', S)$ and let's write tentatively

$$K'_{pqm} h'_q h'_n = \epsilon_{pkm} I'_{kt} \omega'_m (S', S) \omega'_t (S', S) \quad (24)$$

using $h'_r = I'_{rv}\omega'_v(S', S)$ in (24) we get

$$K'_{pkn}I'_{kt}I'_{nm}\omega'_m(S', S)\omega'_t(S', S) = \epsilon_{pkm}I'_{kt}\omega'_m(S', S)\omega'_t(S', S) \quad (25)$$

$$\Rightarrow K'_{pkn}I'_{kt}I'_{nm} = \epsilon_{pkm}I'_{kt} \quad (26)$$

$$\Rightarrow K'_{pkn}I'_{nm} = \epsilon_{pkm} \quad (27)$$

$$\times \epsilon_{pkt} \Rightarrow \epsilon_{pkt}K'_{pkn}I'_{nm} = \delta_{mt} \quad (28)$$

Let's write

$$I'^{-1}_{tn} = \epsilon_{pkt}K'_{pkn}$$

We can truly consider I'^{-1}_{tn} as the inverse of I'_{tn} due to (28) and the fact that I'_{tm} is represented as a symmetric square matrix with real numbers as elements and hence has a non-zero determinant and has indeed an inverse. Multiplying (27) by I'^{-1}_{mt} gives us finally

$$\mathbf{K}'_{\mathbf{pkt}} = \epsilon_{\mathbf{pkm}}\mathbf{I}'^{-1}_{\mathbf{mt}}$$

Q: Why the minus sign in the question?

Let's now calculate I'^{-1}_{tn}

$$I'_{tn} = \begin{pmatrix} I'_{11} & I'_{12} & I'_{13} \\ I'_{12} & I'_{22} & I'_{23} \\ I'_{13} & I'_{23} & I'_{33} \end{pmatrix} \quad (29)$$

The determinant

$$\Delta = I'_{12}I'_{22}I'_{33} + 2I'_{12}I'_{13}I'_{23} - I'^2_{11}I'_{23} - I'^2_{22}I'_{13} - I'^2_{33}I'_{12} \quad (30)$$

giving

$$I'^{-1}_{tn} = \frac{1}{\Delta} \begin{pmatrix} I'_{22}I'_{33} - I'^2_{23} & -I'_{12}I'_{33} + I'_{13}I'_{23} & I'_{12}I'_{23} - I'_{22}I'_{13} \\ -I'_{12}I'_{33} + I'_{13}I'_{23} & I'_{11}I'_{33} - I'^2_{13} & -I'_{11}I'_{23} + I'_{12}I'_{13} \\ I'_{12}I'_{23} - I'_{22}I'_{13} & -I'_{11}I'_{23} + I'_{12}I'_{13} & I'_{11}I'_{22} - I'^2_{12} \end{pmatrix} \quad (31)$$

giving for $\mathbf{K}'_{\mathbf{pkt}} = \epsilon_{\mathbf{pkm}} \mathbf{I}'_{\mathbf{mt}}^{-1}$

$$\left\{ \begin{array}{l} K'_{121} = \frac{1}{\Delta} \left(I'_{12} I'_{23} - I'_{22} I'_{13} \right) \\ K'_{122} = \frac{1}{\Delta} \left(-I'_{11} I'_{23} + I'_{12} I'_{13} \right) \\ K'_{123} = \frac{1}{\Delta} \left(I'_{11} I'_{22} - I'^2_{12} \right) \\ K'_{131} = -\frac{1}{\Delta} \left(-I'_{12} I'_{33} + I'_{13} I'_{23} \right) \\ K'_{132} = \frac{1}{\Delta} \left(I'_{11} I'_{33} - I'^2_{13} \right) \\ K'_{133} = -\frac{1}{\Delta} \left(-I'_{11} I'_{23} + I'_{12} I'_{13} \right) \\ K'_{231} = -\frac{1}{\Delta} \left(I'_{22} I'_{33} - I'^2_{23} \right) \\ K'_{232} = \frac{1}{\Delta} \left(-I'_{11} I'_{23} + I'_{12} I'_{13} \right) \\ K'_{233} = \frac{1}{\Delta} \left(I'_{12} I'_{23} - I'_{22} I'_{13} \right) \end{array} \right. \quad (32)$$

all others can be found by symmetry considerations.



5.38 p189 - Exercise 19

A rigid body turns about a fixed point O in a flat space of N dimensions. prove that if N is odd, there exists at any instant a line OP of particles instantaneously at rest, but that, if N is even, no point other than O is, in general, instantaneously at rest. Show that if $N = 4$, there are points other than O instantaneously at rest if, and only if,

$$\omega_{23}\omega_{14} + \omega_{31}\omega_{24} + \omega_{12}\omega_{34} = 0$$

Consider **5.310**

$$v_p = -\omega_{pr}z_r \tag{1}$$

What we seek, is a vector z_r so that

$$v_p = -\theta\omega_{pr}z_r = 0 \quad \theta \in \mathbb{R} \tag{2}$$

which means that we have to solve the homogeneous system of linear equations

$$\Omega \mathbf{z} = 0 \tag{3}$$

with Ω the skew-symmetric matrix containing the elements of the tensor ω_{pr} . From algebra, we know that when the dimension of a skew-symmetric matrix is odd, then its determinant is zero, and hence the homogeneous system will have an infinity of solutions that can be of the form $z_r = a_r Z_N$ $r = \{1, 2, \dots, N-1\}$, (we take the last coordinate as free parameter). This represents a line along which, all velocities are zero.

On the contrary if N is even, the determinant might be non-zero and the system will not have any solution except the trivial solution $z_r = 0$.

◇

Let's investigate this for $N = 4$. We have for (3):

$$\Omega = \begin{pmatrix} 0 & \omega_{12} & \omega_{13} & \omega_{14} \\ -\omega_{12} & 0 & \omega_{23} & \omega_{24} \\ -\omega_{13} & -\omega_{23} & 0 & \omega_{34} \\ -\omega_{14} & -\omega_{24} & -\omega_{34} & 0 \end{pmatrix} \tag{4}$$

giving

$$\det\{\Omega\} = -\omega_{12} \begin{vmatrix} -\omega_{12} & \omega_{23} & \omega_{24} \\ -\omega_{13} & 0 & \omega_{34} \\ -\omega_{14} & -\omega_{34} & 0 \end{vmatrix} + \omega_{13} \begin{vmatrix} -\omega_{12} & 0 & \omega_{24} \\ -\omega_{13} & -\omega_{23} & \omega_{34} \\ -\omega_{14} & -\omega_{24} & 0 \end{vmatrix} - \omega_{14} \begin{vmatrix} -\omega_{12} & 0 & \omega_{23} \\ -\omega_{13} & -\omega_{23} & 0 \\ -\omega_{14} & -\omega_{24} & -\omega_{34} \end{vmatrix} \quad (5)$$

$$= \begin{cases} -\omega_{12} (-\omega_{12}\omega_{34}\omega_{34} - \omega_{23}\omega_{14}\omega_{34} + \omega_{24}\omega_{13}\omega_{34}) \\ +\omega_{13} (-\omega_{12}\omega_{14}\omega_{34} + \omega_{24}(\omega_{13}\omega_{24} - \omega_{23}\omega_{14})) \\ -\omega_{14} (-\omega_{12}\omega_{23}\omega_{34} + \omega_{23}(\omega_{13}\omega_{24} - \omega_{23}\omega_{14})) \end{cases} \quad (6)$$

$$= \begin{cases} +\omega_{12}\omega_{12}\omega_{34}\omega_{34} + \omega_{12}\omega_{14}\omega_{23}\omega_{34} - \omega_{12}\omega_{13}\omega_{24}\omega_{34} \\ -\omega_{12}\omega_{13}\omega_{14}\omega_{34} + \omega_{13}\omega_{13}\omega_{24}\omega_{24} - \omega_{13}\omega_{14}\omega_{23}\omega_{24} \\ +\omega_{12}\omega_{14}\omega_{23}\omega_{34} - \omega_{13}\omega_{14}\omega_{23}\omega_{24} + \omega_{14}\omega_{14}\omega_{23}\omega_{23} \end{cases} \quad (7)$$

Define

$$\begin{cases} A = \omega_{12}\omega_{34} \\ B = \omega_{13}\omega_{24} \\ C = \omega_{14}\omega_{23} \end{cases} \quad (8)$$

then we can write (7) as

$$\det\{\Omega\} = A^2 + B^2 + C^2 - 2AB - 2BC + 2AB \quad (9)$$

$$= (A - B + C)^2 \quad (10)$$

So, in the space of even dimensions, the system of homogeneous linear equations will have non-trivial solutions, only if

$$\omega_{12}\omega_{34} - \omega_{13}\omega_{24} + \omega_{14}\omega_{23} = 0$$

◇

Let's find now some possible instantaneous lines of rotation.

Suppose $N=4$.

Let's define a line with

$$(z_r) = \theta \begin{pmatrix} \omega_{23} - \omega_{24} + \omega_{34} \\ -\omega_{13} + \omega_{14} + \omega_{34} \\ \omega_{12} - \omega_{14} - \omega_{24} \\ -\omega_{12} + \omega_{13} + \omega_{23} \end{pmatrix} \quad (11)$$

Then calculating the velocities with (1) we get

$$\begin{pmatrix} v_1 \\ v_2 \\ v_3 \\ v_4 \end{pmatrix} = -\theta \begin{pmatrix} 0 & \omega_{12} & \omega_{13} & \omega_{14} \\ -\omega_{12} & 0 & \omega_{23} & \omega_{24} \\ -\omega_{13} & -\omega_{23} & 0 & \omega_{34} \\ -\omega_{14} & -\omega_{24} & -\omega_{34} & 0 \end{pmatrix} \begin{pmatrix} \omega_{23} - \omega_{24} + \omega_{34} \\ -\omega_{13} + \omega_{14} + \omega_{34} \\ \omega_{12} - \omega_{14} - \omega_{24} \\ -\omega_{12} + \omega_{13} + \omega_{23} \end{pmatrix} \quad (12)$$

$$= -\theta \begin{pmatrix} \omega_{12}\omega_{34} - \omega_{13}\omega_{24} + \omega_{14}\omega_{23} \\ -\omega_{12}\omega_{34} + \omega_{13}\omega_{24} - \omega_{14}\omega_{23} \\ -\omega_{12}\omega_{34} + \omega_{13}\omega_{24} - \omega_{14}\omega_{23} \\ -\omega_{12}\omega_{34} + \omega_{13}\omega_{24} - \omega_{14}\omega_{23} \end{pmatrix} \quad (13)$$

So the velocities will vanish when

$$\omega_{12}\omega_{34} - \omega_{13}\omega_{24} + \omega_{14}\omega_{23} = 0$$

◇

Suppose N is odd. Let's define the following vector

$$\omega_{i_1} = \frac{1}{2^{\frac{N-1}{2}} \frac{N-1}{2}!} \epsilon_{i_1 i_2 \dots i_N} \prod_{k=1}^{\frac{N-1}{2}} \omega_{i_{2k} i_{2k+1}} \quad (14)$$

and a line

$$z_{i_1} = \theta \omega_{i_1} \quad (\theta \in \mathbb{R}) \quad (15)$$

First we note that ω_{i_1} (and hence z_{i_1}) is not a null-vector:

Let's consider in (14) the terms consisting of the permutation of the sequence of pairs

$$\{(i_2, i_3), (i_4, i_5), (i_6, i_7), \dots, (i_{N-1}, i_N)\}$$

This sequence contains $\frac{N-1}{2}$ pairs and so can be arranged in $\frac{N-1}{2}!$ ways. As for each pair we have two valid possibilities e.g. (i_2, i_3) and (i_3, i_2) and as a sequence contains $\frac{N-1}{2}$ pairs, we will have for a given order of pairs $2^{\frac{N-1}{2}}$ possibilities. So in (1) there will be $2^{\frac{N-1}{2}} \frac{N-1}{2}!$ terms consisting of the permutation of the sequence of pairs $\{(i_2, i_3), (i_4, i_5), (i_6, i_7), \dots, (i_{N-1}, i_N)\}$.

Without loss of generality, suppose that $\epsilon_{i_1 i_2 \dots i_N}$ is positive and also all $\omega_{i_{2k} i_{2k+1}}$ are positive. Let's first consider a permutation of two pairs in the sequence $\{(i_2, i_3), (i_4, i_5), (i_6, i_7), \dots, (i_{N-1}, i_N)\}$. Obviously, this does not change the product of the $\omega_{i_{2k} i_{2k+1}}$. Also $\epsilon_{i_1 i_2 \dots i_N}$ will hold it's initial sign as the considered permutation needs two permutation of indices.

Next consider a permutation in one of the pairs of the sequence. Obviously $\epsilon_{i_1 i_2 \dots i_N}$ will change sign but also the picked $\omega_{i_{2k} i_{2k+1}}$ (skew-symmetric).

Conclusion, all $2^{\frac{N-1}{2}} \frac{N-1}{2}!$ terms can be reduced to the sum of $2^{\frac{N-1}{2}} \frac{N-1}{2}!$ of a same quantity and the ω_{i_1} will not trivially be zero.

Let's consider now **5.310**

$$v_p = -\omega_{pi_1} z_{i_1} \quad (16)$$

$$(14): \quad v_p = -\frac{1}{2^{\frac{N-1}{2}} \frac{N-1}{2}!} \theta \epsilon_{i_1 i_2 \dots i_N} \omega_{pi_1} \prod_{k=1}^{\frac{N-1}{2}} \omega_{i_{2k} i_{2k+1}} \quad (17)$$

On the right side, for having a non-zero term, we need that $p \neq i_1$ (ω_{st} skew-symmetric). This leaves us with only $N - 1$ possible choices in the indices but as $\epsilon_{i_1 i_2 \dots i_N}$ needs N mutual different indices it is obvious that each term in (17) will have a $\epsilon_{i_1 i_2 \dots i_N} = 0$

Conclusion, all v_p are zero and hence the defined line in (15) is an instantaneous line of rotation.



5.39 p189 - Exercise 20

The equations **5.329** do not determine J_{nprq} uniquely. Why? As an alternative to **5.330**, we can require J_{nprq} to be skew-symmetric in the last two suffixes. Show that this defines J_{nprq} uniquely as follows:

$$J_{nprq} = \frac{1}{2} \sum m (\delta_{nr} z_p z_q + \delta_{pq} z_n z_r - \delta_{nq} z_p z_r - \delta_{pr} z_n z_q)$$

Prove that J_{nprq} , as defined here, has the same symmetries as the covariant curvature tensor (see **3.115**, **3.116**) and that, for $N = 3$, we have

$$I_{st} = \frac{1}{2} \epsilon_{snp} \epsilon_{trq} J_{nprq}, \quad J_{nprq} = \frac{1}{2} \epsilon_{snp} \epsilon_{trq} I_{st}$$

The equations **5.329**, $h_{np} = J_{nprq} \omega_{rq}$ do not determine J_{nprq} uniquely because ω_{rq} is skew symmetric, so all elements at the positions $J_{np(rr)}$ can be chosen arbitrarily and still comply with the equation.

Consider now the expression

$$J'_{nprq} = \frac{1}{2} (J_{nprq} - J'_{npqr}) \quad (1)$$

$$\Rightarrow h'_{np} = J'_{nprq} \omega_{rq} \quad (2)$$

$$= \frac{1}{2} (J_{nprq} \omega_{rq} - J_{npqr} \omega_{rq}) \quad (3)$$

$$= \frac{1}{2} (J_{nprq} \omega_{rq} + J_{npqr} \omega_{qr}) \quad (4)$$

$$= \frac{1}{2} (J_{nprq} \omega_{rq} + J_{nprq} \omega_{rq}) \quad (5)$$

$$= h_{np} \quad (6)$$

So this expression $J_{nprq} = \frac{1}{2} \sum m (\delta_{nr} z_p z_q + \delta_{pq} z_n z_r - \delta_{nq} z_p z_r - \delta_{pr} z_n z_q)$ still describes the dynamical system and we note that this expression is skew-symmetric in the two last suffixes:

$$J_{np(rr)} = \frac{1}{2} \sum m (\delta_{nr} z_p z_r + \delta_{pr} z_n z_r - \delta_{nr} z_p z_r - \delta_{pr} z_n z_r) = 0 \quad (7)$$

$$J_{npqr} = \frac{1}{2} \sum m (\delta_{nq} z_p z_r + \delta_{pr} z_n z_q - \delta_{nr} z_p z_q - \delta_{pq} z_n z_r) \quad (8)$$

$$= -\frac{1}{2} \sum m (-\delta_{nq} z_p z_r - \delta_{pr} z_n z_q + \delta_{nr} z_p z_q + \delta_{pq} z_n z_r) \quad (9)$$

$$= -J_{nprq} \quad (10)$$

Symmetries to prove:

$$\begin{cases} J_{nprq} = -J_{pnrq}, & J_{nprq} = -J_{npqr}, & J_{nprq} = J_{rqnp} \\ J_{nprq} + J_{nrqp} + J_{nqpr} = 0 \end{cases} \quad (11)$$

The second identity of (11) is already proven as J_{nprq} is skew-symmetric in the last two suffixes.

For the rest:

$$J_{nprq} = \frac{1}{2} \sum m (\delta_{nr} z_p z_q + \delta_{pq} z_n z_r - \delta_{nq} z_p z_r - \delta_{pr} z_n z_q) \quad (12)$$

$$= -\frac{1}{2} \sum m (-\delta_{nr} z_p z_q - \delta_{pq} z_n z_r + \delta_{nq} z_p z_r + \delta_{pr} z_n z_q) \quad (13)$$

$$= J_{pnrq} \quad (14)$$

and

$$J_{nprq} = \frac{1}{2} \sum m (\delta_{nr} z_p z_q + \delta_{pq} z_n z_r - \delta_{nq} z_p z_r - \delta_{pr} z_n z_q) \quad (15)$$

$$J_{rqnp} = \frac{1}{2} \sum m (\delta_{rn} z_q z_p + \delta_{qp} z_r z_n - \delta_{rp} z_q z_n - \delta_{qn} z_r z_p) \quad (16)$$

$$= J_{pnrq} \quad (17)$$

and

$$J_{nprq} + J_{nrqp} + J_{nqpr} = \begin{cases} +\frac{1}{2} \sum m (\delta_{nr} z_p z_q + \delta_{pq} z_n z_r - \delta_{nq} z_p z_r - \delta_{pr} z_n z_q) \\ +\frac{1}{2} \sum m (\delta_{nq} z_p z_r + \delta_{rp} z_n z_q - \delta_{np} z_q z_r - \delta_{rq} z_n z_p) \\ +\frac{1}{2} \sum m (\delta_{np} z_r z_q + \delta_{qr} z_n z_p - \delta_{nr} z_q z_p - \delta_{qp} z_n z_r) \end{cases} = 0 \quad (18)$$

For the last part: From **5.33**, (J'_{nprq} being a not necessarily skew-symmetric tensor)

$$I_{st} = \frac{1}{2} J'_{nprq} \epsilon_{rqt} \epsilon_{snp} \quad (19)$$

or

$$I_{st} = \frac{1}{2} J'_{npqr} \epsilon_{qrt} \epsilon_{snp} \quad (20)$$

$$= -\frac{1}{2} J'_{npqr} \epsilon_{rqt} \epsilon_{snp} \quad (21)$$

Adding (19) and (21) gives

$$2I_{st} = \frac{1}{2} \underbrace{(J'_{npqr} - J'_{npqr})}_{=J_{npqr}} \epsilon_{rqt} \epsilon_{snp} \quad (22)$$

$$\Rightarrow I_{st} = \frac{1}{2} J_{npqr} \epsilon_{rqt} \epsilon_{snp} \quad (23)$$

And

$$I_{st} \epsilon_{trq} \epsilon_{snp} = \frac{1}{2} J'_{kjuv} \underbrace{\epsilon_{tuv} \epsilon_{trq}}_{=\delta_{ur} \delta_{vq} - \delta_{uq} \delta_{vr}} \underbrace{\epsilon_{skj} \epsilon_{snp}}_{=\delta_{kn} \delta_{jp} - \delta_{kp} \delta_{jn}} \quad (24)$$

$$= -\frac{1}{2} J'_{npqr} \epsilon_{rqt} \epsilon_{snp} \quad (25)$$

expanding the right product we get

$$I_{st}\epsilon_{trq}\epsilon_{snp} = \frac{1}{2} (J_{nprq} + J_{pnqr} - J_{npqr} - J_{pnrq}) \quad (26)$$

And considering the symmetries described previously we get

$$I_{st}\epsilon_{trq}\epsilon_{snp} = \frac{1}{2} 4J_{nprq} \quad (27)$$

$$= 2J_{nprq} \quad (28)$$

$$\Rightarrow J_{nprq} = \frac{1}{2} I_{st}\epsilon_{trq}\epsilon_{snp} \quad (29)$$



Applications to Hydrodynamics, Elasticity, and Electromagnetic radiation

5.1 p191 - Exercise

A fluid rotates as a rigid body about the axis of z_3 with variable angular velocity $\omega(t)$. Write out explicitly the three Lagrangian equations **6.101** and the three Eulerian equations **6.103**.

The motion described reduces to a motion in a V_2 plane with z_3 a constant for a definite particle.

Lagrangian

A particular particle with starting coordinates $(z_1^{(*)}, z_2^{(*)}, z_3^{(*)})$ will describe a circle with radius $\sqrt{z_1^{(*)2} + z_2^{(*)2}}$ in the plane V_2 parallel with the 1, 2 axes. Taking axis 1 as reference to determine the instantaneous angle θ of the vertex OP (origin and particle) we get

$$\begin{cases} z_1 = \sqrt{z_1^{(*)2} + z_2^{(*)2}} \cos(\theta(t) + \phi_0) \\ z_2 = \sqrt{z_1^{(*)2} + z_2^{(*)2}} \sin(\theta(t) + \phi_0) \\ z_3 = z_3^{(*)} \end{cases} \quad (1)$$

with

$$\phi_0 = \arctan \frac{z_2^{(*)}}{z_1^{(*)}} \quad (2)$$

Note that $\omega(t)$ is not a constant, so

$$\theta(t) = \int_0^t \omega(\tau) d\tau \quad (3)$$

and get

$$\begin{cases} z_1 = \sqrt{z_1^{(*)2} + z_2^{(*)2}} \cos\left(\int_0^t \omega(\tau) d\tau + \phi_0\right) \\ z_2 = \sqrt{z_1^{(*)2} + z_2^{(*)2}} \sin\left(\int_0^t \omega(\tau) d\tau + \phi_0\right) \\ z_3 = z_3^{(*)} \\ \phi_0 = \arctan \frac{z_2^{(*)}}{z_1^{(*)}} \end{cases} \quad (4)$$

◇

Eulerian

The equations get simplified and reduce to a motion of a particle on a circle.

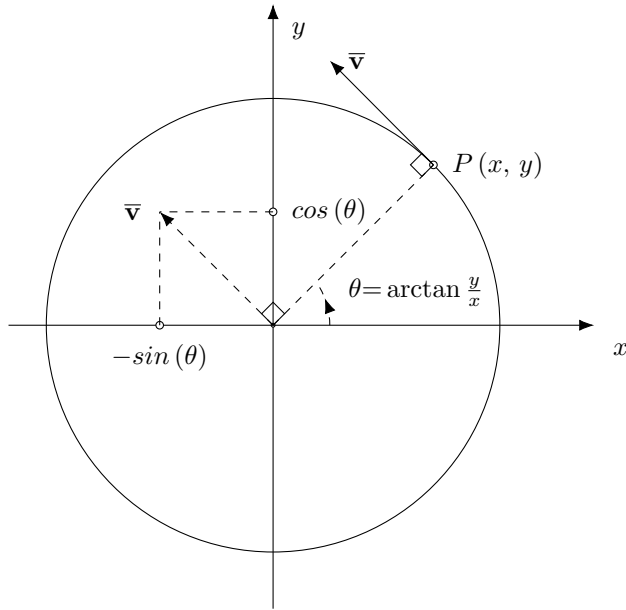


Figure 5.1: Eulerian viewpoint of a spinning fluid

$$\left\{ \begin{array}{l} v_1 = -\sqrt{z_1^2 + z_2^2} \omega(t) \sin\left(\arctan \frac{z_2}{z_1}\right) \\ v_2 = \sqrt{z_1^2 + z_2^2} \omega(t) \cos\left(\arctan \frac{z_2}{z_1}\right) \\ v_3 = 0 \end{array} \right. \quad (5)$$



5.2 p191 - Exercise

Compute the components of acceleration for the motion described in the preceding exercise.

We have

$$\begin{cases} v_1 = -\sqrt{z_1^2 + z_2^2} \omega(t) \sin\left(\arctan \frac{z_2}{z_1}\right) \\ v_2 = \sqrt{z_1^2 + z_2^2} \omega(t) \cos\left(\arctan \frac{z_2}{z_1}\right) \\ v_3 = 0 \end{cases} \quad (1)$$

and

$$f_r = \partial_t v_r + v_{r,s} v_s \quad (2)$$

$$\begin{cases} \partial_t v_1 = -\sqrt{z_1^2 + z_2^2} \dot{\omega}(t) \sin\left(\arctan \frac{z_2}{z_1}\right) \\ \partial_t v_2 = \sqrt{z_1^2 + z_2^2} \dot{\omega}(t) \cos\left(\arctan \frac{z_2}{z_1}\right) \\ v_{1,1} = -\omega(t) \left[\frac{z_1}{\sqrt{z_1^2 + z_2^2}} \sin\left(\arctan \frac{z_2}{z_1}\right) - \sqrt{z_1^2 + z_2^2} \cos\left(\arctan \frac{z_2}{z_1}\right) \frac{z_2}{z_1} \frac{1}{1 + \frac{z_2^2}{z_1^2}} \right] \\ v_{1,2} = -\omega(t) \left[\frac{z_2}{\sqrt{z_1^2 + z_2^2}} \sin\left(\arctan \frac{z_2}{z_1}\right) + \sqrt{z_1^2 + z_2^2} \cos\left(\arctan \frac{z_2}{z_1}\right) \frac{1}{z_1} \frac{1}{1 + \frac{z_2^2}{z_1^2}} \right] \\ v_{2,1} = \omega(t) \left[\frac{z_1}{\sqrt{z_1^2 + z_2^2}} \cos\left(\arctan \frac{z_2}{z_1}\right) + \sqrt{z_1^2 + z_2^2} \sin\left(\arctan \frac{z_2}{z_1}\right) \frac{z_2}{z_1} \frac{1}{1 + \frac{z_2^2}{z_1^2}} \right] \\ v_{2,2} = \omega(t) \left[\frac{z_2}{\sqrt{z_1^2 + z_2^2}} \cos\left(\arctan \frac{z_2}{z_1}\right) - \sqrt{z_1^2 + z_2^2} \sin\left(\arctan \frac{z_2}{z_1}\right) \frac{1}{z_1} \frac{1}{1 + \frac{z_2^2}{z_1^2}} \right] \end{cases} \quad (3)$$

$$= \begin{cases} \partial_t v_1 = -\sqrt{z_1^2 + z_2^2} \dot{\omega}(t) \sin\left(\arctan \frac{z_2}{z_1}\right) \\ \partial_t v_2 = \sqrt{z_1^2 + z_2^2} \dot{\omega}(t) \cos\left(\arctan \frac{z_2}{z_1}\right) \\ v_{1,1} = -\frac{\omega(t)}{\sqrt{z_1^2 + z_2^2}} \left[z_1 \sin\left(\arctan \frac{z_2}{z_1}\right) - z_2 \cos\left(\arctan \frac{z_2}{z_1}\right) \right] \\ v_{1,2} = -\frac{\omega(t)}{\sqrt{z_1^2 + z_2^2}} \left[z_2 \sin\left(\arctan \frac{z_2}{z_1}\right) + z_1 \cos\left(\arctan \frac{z_2}{z_1}\right) \right] \\ v_{2,1} = \frac{\omega(t)}{\sqrt{z_1^2 + z_2^2}} \left[z_1 \cos\left(\arctan \frac{z_2}{z_1}\right) + z_2 \sin\left(\arctan \frac{z_2}{z_1}\right) \right] \\ v_{2,2} = \frac{\omega(t)}{\sqrt{z_1^2 + z_2^2}} \left[z_2 \cos\left(\arctan \frac{z_2}{z_1}\right) - z_1 \sin\left(\arctan \frac{z_2}{z_1}\right) \right] \end{cases} \quad (4)$$

and get

$$v_{1,s} v_s = \begin{cases} -\sqrt{z_1^2 + z_2^2} \omega(t) \sin\left(\arctan \frac{z_2}{z_1}\right) \frac{\omega(t)}{\sqrt{z_1^2 + z_2^2}} \left[z_1 \sin\left(\arctan \frac{z_2}{z_1}\right) - z_2 \cos\left(\arctan \frac{z_2}{z_1}\right) \right] \\ -\sqrt{z_1^2 + z_2^2} \omega(t) \cos\left(\arctan \frac{z_2}{z_1}\right) \frac{\omega(t)}{\sqrt{z_1^2 + z_2^2}} \left[z_2 \sin\left(\arctan \frac{z_2}{z_1}\right) + z_1 \cos\left(\arctan \frac{z_2}{z_1}\right) \right] \end{cases} \quad (5)$$

$$= -z_1 \omega^2(t) \quad (6)$$

$$v_{2,s} v_s = \begin{cases} \sqrt{z_1^2 + z_2^2} \omega(t) \sin\left(\arctan \frac{z_2}{z_1}\right) \frac{\omega(t)}{\sqrt{z_1^2 + z_2^2}} \left[z_1 \cos\left(\arctan \frac{z_2}{z_1}\right) + z_2 \sin\left(\arctan \frac{z_2}{z_1}\right) \right] \\ +\sqrt{z_1^2 + z_2^2} \omega(t) \cos\left(\arctan \frac{z_2}{z_1}\right) \frac{\omega(t)}{\sqrt{z_1^2 + z_2^2}} \left[z_2 \cos\left(\arctan \frac{z_2}{z_1}\right) - z_1 \sin\left(\arctan \frac{z_2}{z_1}\right) \right] \end{cases} \quad (7)$$

$$= z_2 \omega^2(t) \quad (8)$$

giving with the second derivative term

$$= \begin{cases} f_1 = -\dot{\omega}(t) \sqrt{z_1^2 + z_2^2} \sin\left(\arctan \frac{z_2}{z_1}\right) - z_1 \omega^2(t) \\ f_2 = \dot{\omega}(t) \sqrt{z_1^2 + z_2^2} \cos\left(\arctan \frac{z_2}{z_1}\right) + z_2 \omega^2(t) \\ f_3 = 0 \end{cases} \quad (9)$$



5.3 p193 - Exercise

Verify that the operator $\frac{\partial}{\partial t}$ does not alter tensor character.

Be X^r and Y^r , two tensors so that $I = X_r Y^r$ is an invariant. Obviously, $\frac{\partial I}{\partial t}$ will also be invariant and

$$\frac{\partial I}{\partial t} = \frac{\partial X_r}{\partial t} Y^r + X_r \frac{\partial Y^r}{\partial t} \quad (1)$$

Meaning that the right side is a sum of two invariants, from which we conclude (see page 20, **1.607**) that $\frac{\partial X_r}{\partial t}$ and $\frac{\partial Y^r}{\partial t}$ are tensors.



5.4 p193 - Clarification to 6.112

$$\mathbf{6.112.} \quad \int F n_r dS = \int F_{,r} dV$$

Green's theorem is generally presented in the form

$$\int \bar{F} \cdot \bar{n} dS = \int \bar{\nabla} \cdot \bar{F} dV$$

or

$$\int F_r n_r dS = \int F_{r,r} dV$$

We can define

$$\bar{F} = F \bar{\mathbf{1}}_r$$

$\bar{F} \cdot \bar{n}$ will then become $F n_r$, while $\bar{\nabla} \cdot \bar{F}$ will become $\partial_r F$, giving the expression **6.112.**



5.5 p196 - Exercise

Write out **6.126** and **6.127b** explicitly for spherical polar coordinates.

For spherical polar coordinates we have

$$(v^r) = \begin{pmatrix} \dot{r} \\ r\dot{\theta} \\ r \sin \theta \dot{\phi} \end{pmatrix} \quad (1)$$

and (see **2.546** page 58):

$$v_{|r}^r = \frac{1}{r^2} \partial_r (r^2 v^1) + \frac{1}{\sin \theta} \partial_\theta (\sin \theta v^2) + \partial_\phi v^3 \quad (2)$$

$$= \frac{1}{r^2} (2r v^1 + r^2 \partial_r v^1) + \frac{1}{\sin \theta} (v^2 \cos \theta + \sin \theta \partial_\theta v^2) \quad (3)$$

$$= \frac{2}{r} \dot{r} + r \dot{\theta} \cot \theta \quad (4)$$

and

$$\partial_t \rho + (\rho v^r)_{|r} = 0 \quad (5)$$

$$\Leftrightarrow \partial_t \rho + \rho_{|r} v^r + \rho v_{|r}^r = 0 \quad (6)$$

$$\Leftrightarrow \frac{d\rho}{dt} + \rho \left(\frac{2}{r} \dot{r} + r \dot{\theta} \cot \theta \right) = 0 \quad (7)$$



5.6 p198 - Exercise

If ϵ^{rmn} is defined in precisely the same way as ϵ_{rmn} , prove that

$$\epsilon'^{uvw} = J \epsilon^{rmn} \frac{\partial x'^u}{\partial x^r} \frac{\partial x'^v}{\partial x^m} \frac{\partial x'^w}{\partial x^n}$$

We follow the pretty same line of reasoning as for ϵ_{rst} . Going from x'^r to x^s we have (expanding the determinant of the inverse Jacobian along the rows instead of the columns):

$$J^{-1} = \left| \frac{\partial x'^p}{\partial x^q} \right| = \epsilon^{rmn} \frac{\partial x'^1}{\partial x^r} \frac{\partial x'^2}{\partial x^m} \frac{\partial x'^3}{\partial x^n} \quad (1)$$

$$\times \epsilon^{uvw} \quad J^{-1} \epsilon^{uvw} = \epsilon^{rmn} \frac{\partial x'^u}{\partial x^r} \frac{\partial x'^v}{\partial x^m} \frac{\partial x'^w}{\partial x^n} \quad (2)$$

$$\times J \quad \epsilon^{uvw} = J \epsilon^{rmn} \frac{\partial x'^u}{\partial x^r} \frac{\partial x'^v}{\partial x^m} \frac{\partial x'^w}{\partial x^n} \quad (3)$$

$$(4)$$



5.7 p198 - Exercise

Prove that $\frac{\epsilon^{rmn}}{\sqrt{a}}$ is an (absolute) contravariant tensor of the third order.

$$\sqrt{a'} = J\sqrt{a} \quad (1)$$

$$\epsilon'^{uvw} = J\epsilon^{rmn} \frac{\partial x'^u}{\partial x^r} \frac{\partial x'^v}{\partial x^m} \frac{\partial x'^w}{\partial x^n} \quad (2)$$

$$(1) \text{ in } (2) \quad \epsilon'^{uvw} = \frac{\sqrt{a'}}{\sqrt{a}} \epsilon^{rmn} \frac{\partial x'^u}{\partial x^r} \frac{\partial x'^v}{\partial x^m} \frac{\partial x'^w}{\partial x^n} \quad (3)$$

$$\Rightarrow \quad \frac{\epsilon'^{uvw}}{\sqrt{a'}} = \frac{\epsilon^{rmn}}{\sqrt{a}} \frac{\partial x'^u}{\partial x^r} \frac{\partial x'^v}{\partial x^m} \frac{\partial x'^w}{\partial x^n} \quad (4)$$

which is the required transformation rule for a "normal" (absolute) tensor.



5.8 p199 - Clarification to pressure invariance to direction of the surface element.

Pressure is independent of the direction

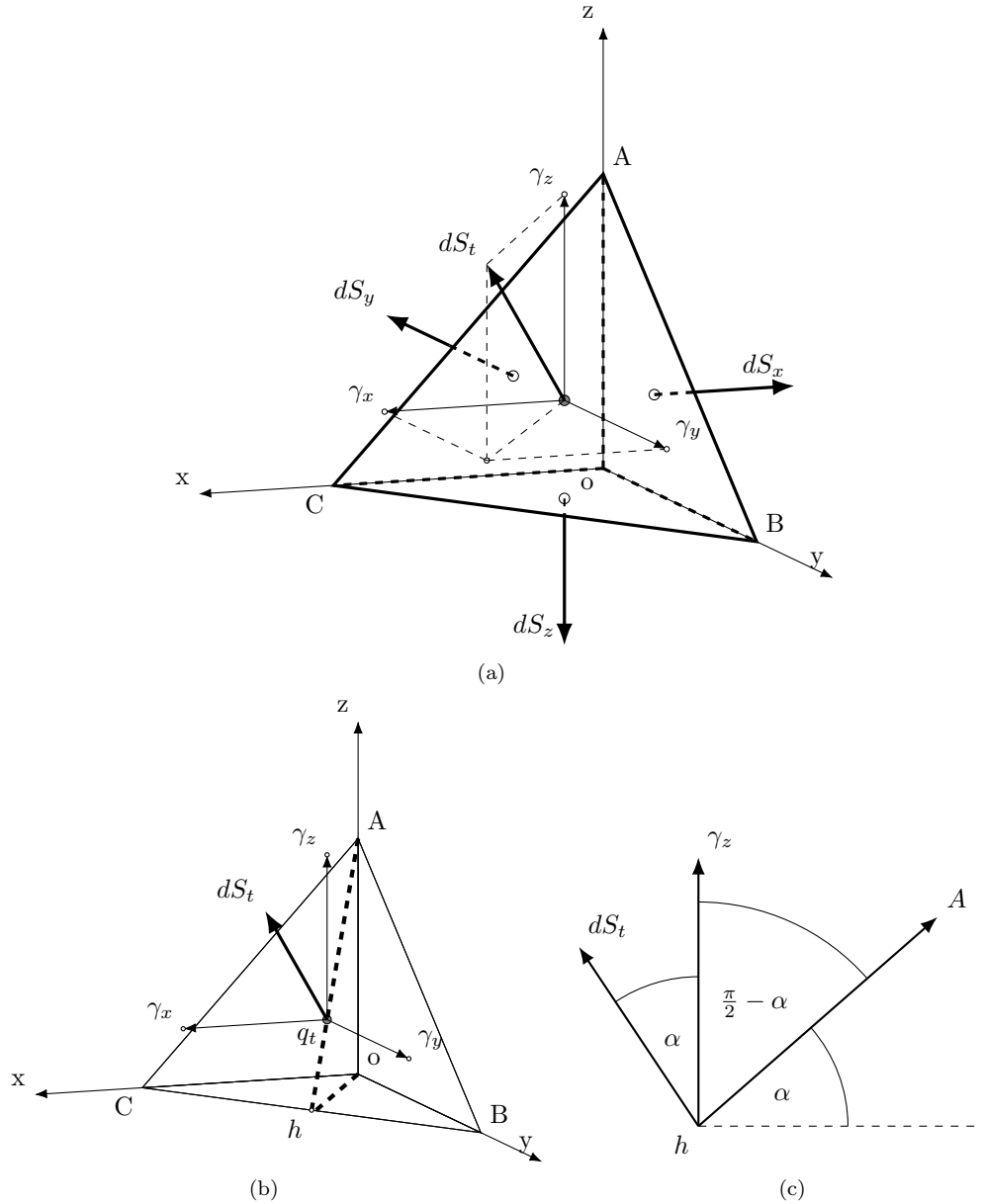


Figure 5.2: Pressure on a trirectangular tetrahedron

To see that the pressure is independent of the direction of the surface element on which we measure it, let's consider a trirectangular tetrahedron $OABC$ as depicted in figure 5.2(a). Let's define P_x, P_y, P_z, P_t the pressure measured on the 4 surfaces with normal vectors dS_x, dS_y, dS_z, dS_t .

Let's neglect second order terms due to acceleration and external forces. For the forces along axis z (the same reasoning is valid for the two others) we will have $P_z dS_z = P_t dS_t \gamma_z$ where γ_z is the cosine of the angle formed by normal on dS_t and the z -axis.

Let's investigate the relationship between dS_t and dS_x, dS_y, dS_z .

Be hA the line element lying in the plane ABC (see figure 5.2(b)) and hO the line element lying in the plane OBC . As the area of a triangle $= \frac{1}{2} \times \text{base} \times \text{perpendicular height}$ we get $dS_z = \frac{1}{2} |hO| |BC|$. But $|hO| = |hA| \cos \alpha$ (see figure 5.2(c)) and so $dS_z = \frac{1}{2} |BC| |hA| \cos \alpha = dS_t \gamma_z$ and get

$$P_z dS_z = P_t dS_t \gamma_z \quad (1)$$

$$\Rightarrow P_z dS_t \gamma_z = P_t dS_t \gamma_z \quad (2)$$

$$\Rightarrow P_z = P_t \quad (3)$$



5.9 p201 - Exercise

Write down the contravariant form of **6.147**

$$\mathbf{6.147} \quad \partial_t v_r + v_s v_{r|s} = X_r - \rho^{-1} p_{,r}$$

$$\mathbf{6.147} \quad \partial_t v_r + v_s v_{r|s} = X_r - \rho^{-1} p_{,r} \quad (1)$$

$$\times a^{mr} \quad \partial_t a^{mr} v_r + v_s a^{mr} v_{r|s} = a^{mr} X_r - \rho^{-1} a^{mr} p_{,r} \quad (2)$$

By **2.527** page 53 we have $a_t^{rs} = 0$ and thus

$$v_{|s}^m = (a^{mr} v_r)_{|s} = (a^{mr})_{|n} v_r + a^{mr} v_{r|s} = a^{mr} v_{r|s} \quad (3)$$

$$(2) \Rightarrow \quad \partial_t v^m + v_s v_{|s}^m = X^m - \rho^{-1} a^{mr} p_{,r} \quad (4)$$

$$\Rightarrow \quad \partial_t v^m + v_s v_{|s}^m = X^m - \rho^{-1} p'_{,r} \quad (5)$$

Note that $p_{,r}$ in (1) and (5) are not the same vector function as $p_{,r}$ can be written as $\bar{\nabla} p$ which is coordinate system dependent.



5.10 p202 - Exercise

Verify by means of **3.204** that **6.157** and **6.156** are the same equation.

$$\left\{ \begin{array}{ll} \mathbf{3.204} & \Gamma_{rn}^n = \frac{1}{2} \partial_r \log a = \partial_r \log \sqrt{a} \\ \mathbf{6.157} & (\sqrt{a} a^{mn} \phi_{,m})_{,n} = 0 \\ \mathbf{6.156} & a^{mn} \phi_{|mn} = 0 \end{array} \right. \quad (1)$$

Considering also

$$\left\{ \begin{array}{l} a_{|k}^{mn} = 0 \\ T_{|n}^m = \partial_n T_m + \Gamma_{kn}^m T_k \end{array} \right. \quad (2)$$

So **6.156** can be written as

$$a^{mn} \phi_{|mn} = 0 \quad (3)$$

$$\Leftrightarrow (a^{mn} \phi_{|m})_{|n} = 0 \quad (4)$$

$$T^n = a^{mn} \phi_{|m} \Rightarrow \partial_n T^n + \Gamma_{kn}^n T^k = 0 \quad (5)$$

$$\Rightarrow \partial_n (a^{mn} \phi_{|m}) + \Gamma_{kn}^n a^{pk} \phi_{|p} = 0 \quad (6)$$

$$\Leftrightarrow \partial_n (a^{mn}) \phi_{,m} + a^{mn} \phi_{,mn} + \Gamma_{kn}^n a^{pk} \phi_{,p} = 0 \quad (7)$$

$$(2) \Rightarrow \partial_n (a^{mn}) \phi_{,m} + a^{mn} \phi_{,mn} + \partial_k \log \sqrt{a} a^{pk} \phi_{,p} = 0 \quad (8)$$

$$\Leftrightarrow (a_{,n}^{mn}) \phi_{,m} + a^{mn} \phi_{,mn} + \frac{1}{\sqrt{a}} (\sqrt{a} a^{pk})_{,k} \phi_{,p} = 0 \quad (9)$$

$$\Leftrightarrow \sqrt{a} \phi_{,m} (a^{mn})_{,n} + \sqrt{a} a^{mn} \phi_{,mn} + a^{mn} \phi_{,m} (\sqrt{a})_{,n} = 0 \quad (10)$$

$$\Leftrightarrow (\sqrt{a} a^{mn} \phi_{,m})_{,n} = 0 \quad (11)$$



5.11 p205 - Exercise

Show that a small strain is a rigid body displacement if, and only if, $e_{rs} = 0$. In the case of finite strain, deduce from **6.206** the conditions which must be satisfied by the partial derivatives of the displacement in order that it may be a rigid body displacement.

Suppose we deal with a rigid body. Then the position of two particles of the rigid body are given by

$$\begin{cases} p_r = z_r + u_r(z) \\ p'_r = z'_r + u_r(z') \end{cases} \quad (1)$$

and

$$\begin{cases} L_0 = z_r - z'_r \\ L_1 = z'_r + u_r(z') - z_r - u_r(z) \end{cases} \quad (2)$$

A rigid body means $L_1 = L_0$, giving $u_r(z') = u_r(z)$ i.e $u_r(z)$ is a constant and thus $u_{r,s}(z) = 0$. As $e_{rs} = \frac{1}{2}(u_{r,s}(z) + u_{s,r}(z))$ we get $e_{rs} = 0$

Suppose now that $e_{rs} = 0$

We have $e = e_{rs}\lambda_r\lambda_s = 0$ and $e = u_{r,s}(z)\lambda_r\lambda_s$. As the λ_r are arbitrary, in the sense that we are free to choose whatever curve to approach the initial point, we conclude that $u_{r,s}(z) = 0$. So $u_r(z)$ is a constant, meaning that the mutual distance between two arbitrary points, do not change. The body is a rigid body.

◇

For a finite strain we have **6.206**:

$$\lim \frac{L_1^2 - L_0^2}{L_0^2} = 2u_{r,s}(z)\lambda_r\lambda_s + u_{m,r}(z)u_{m,s}(z)\lambda_r\lambda_s \quad (3)$$

This limit is 0 and so we get as condition

$$(2u_{r,s}(z) + u_{m,r}(z)u_{m,s}(z))\lambda_r\lambda_s = 0 \quad (4)$$

As the λ_r are arbitrary, in the sense that we are free to choose whatever curve to approach the initial point, we conclude that $2u_{r,s}(z) + u_{m,r}(z)u_{m,s}(z)$ must be zero.

$$2u_{r,s}(z) + u_{m,r}(z)u_{m,s}(z) = 0$$

◆

5.12 p207 - Clarification

Then, clearly, since the the volume of the tetrahedron is less than a^3 ,

$$\mathbf{6.217} \quad \lim_{a \rightarrow 0} \frac{1}{a^2} \frac{dM_r}{dt} = 0, \quad \lim_{a \rightarrow 0} \frac{1}{a^2} \int X_r dV = 0$$

\vdots

But $\lim_{a \rightarrow 0} \frac{S}{a^2}$ is not zero,...

First, note that the volume of a trirectangular tetrahedron is $V = \frac{1}{6}abc$ with a, b, c the bases of the 3 rectangular triangles (see clarification for page 199), so if $a \geq b, c$ we have $V < a^3$.

There is no assurance that $\lim_{a \rightarrow 0} \frac{1}{a^3} \frac{dM_r}{dt} = 0$. Indeed, consider **5.334**. For a continuous medium, this equation can be written as

$$I_{st} = \int_V \rho \epsilon_{ptq} \epsilon_{psn} z_s z_t dV \quad (1)$$

If V goes to zero, the quantities under the integral can be approximated by constant values and hence, the dynamics of the tetrahedron are govern by

$$\lim_{V \rightarrow 0} I_{st} = \rho \epsilon_{ptq} \epsilon_{psn} z_s z_t V \quad (2)$$

$$\mathbf{5.332:} \quad \frac{dI_{st}\omega_t}{dt} = M_s \quad (3)$$

$$\Rightarrow \quad \lim_{V \rightarrow 0} \frac{dM_s}{dt} = \lim_{V \rightarrow 0} V \frac{d(\rho \epsilon_{ptq} \epsilon_{psn} z_s z_t \omega_t)}{dt} \quad (4)$$

$$\Rightarrow \quad \lim_{a \rightarrow 0} \frac{1}{a^3} \frac{dM_s}{dt} = \lim_{a \rightarrow 0} \frac{1}{a^3} V \frac{d(\rho \epsilon_{ptq} \epsilon_{psn} z_s z_t \omega_t)}{dt} \quad (5)$$

$$\Rightarrow \quad \lim_{a \rightarrow 0} \frac{1}{a^3} \frac{dM_s}{dt} < \lim_{a \rightarrow 0} \frac{1}{a^3} a^3 \frac{d(\rho \epsilon_{ptq} \epsilon_{psn} z_s z_t \omega_t)}{dt} \quad (6)$$

$$\Rightarrow \quad \lim_{a \rightarrow 0} \frac{1}{a^3} \frac{dM_s}{dt} < \lim_{a \rightarrow 0} \frac{d(\rho \epsilon_{ptq} \epsilon_{psn} z_s z_t \omega_t)}{dt} \quad (7)$$

but there is no reason to admit that $\lim_{V \rightarrow 0} \frac{d(\rho \epsilon_{ptq} \epsilon_{psn} z_s z_t \omega_t)}{dt} = 0$.

On the other hand, replacing a_3 with a^2 in (5) gives

$$\lim_{a \rightarrow 0} \frac{1}{a^2} \frac{dM_s}{dt} = \lim_{a \rightarrow 0} \frac{1}{a^2} V \frac{d(\rho \epsilon_{ptq} \epsilon_{psn} z_s z_t \omega_t)}{dt} \quad (8)$$

$$\Rightarrow \quad \lim_{a \rightarrow 0} \frac{1}{a^2} \frac{dM_s}{dt} < \lim_{a \rightarrow 0} \frac{1}{a^2} a^3 \frac{d(\rho \epsilon_{ptq} \epsilon_{psn} z_s z_t \omega_t)}{dt} \quad (9)$$

$$\Rightarrow \quad \lim_{a \rightarrow 0} \frac{1}{a^2} \frac{dM_s}{dt} < \lim_{a \rightarrow 0} a \frac{d(\rho \epsilon_{ptq} \epsilon_{psn} z_s z_t \omega_t)}{dt} \quad (10)$$

$$\Rightarrow \quad \lim_{a \rightarrow 0} \frac{1}{a^2} \frac{dM_s}{dt} = 0 \quad (11)$$

For $\lim_{a \rightarrow 0} \frac{1}{a^2} \int X_r dV = 0$ the reasoning is even simpler as for a volume going to zero, we can consider X_r as constant and thus

$$\lim_{a \rightarrow 0} \frac{1}{a^2} \int X_r dV = \lim_{a \rightarrow 0} \frac{1}{a^2} X_r \int dV < \lim_{a \rightarrow 0} \frac{1}{a^2} X_r a^3 = 0 \quad (12)$$

◇

But $\lim_{a \rightarrow 0} \frac{S}{a^2}$ is not zero,...

Be S_t the area of the "sloped" triangle in the tetrahedron. Then, the total area of the tetrahedron is:

$$S = \frac{1}{2} (ab + bc + ac) + S_t \quad (13)$$

$$S_t > \frac{1}{2} ab, S_t > \frac{1}{2} bc, S_t > \frac{1}{2} ac \quad (14)$$

$$\Rightarrow S > \frac{1}{2} (ab + bc + ac) + \frac{1}{2} ab \quad (15)$$

$$\Rightarrow \frac{S}{a^2} > \frac{1}{2} \left(\frac{bc}{a^2} + \frac{c}{a} \right) + b \quad (16)$$

If we shrink the tetrahedron uniformly and put $a = \epsilon a_0, b = \epsilon b_0, c = \epsilon c_0$ then (16) can be written as

$$\lim_{\epsilon \rightarrow 0} \frac{S}{a^2} > \frac{1}{2} \left(\frac{b_0 c_0}{a_0^2} + \frac{c_0}{a_0} \right) + b_0 \lim_{\epsilon \rightarrow 0} \epsilon \quad (17)$$

which is indeed not zero.

◆

5.13 p208 - Exercise

Show that the stress across a plane $z_1 = \text{const.}$ has the components E_{11} , E_{21} , E_{31} . What are the components across planes $z_2 = \text{const.}$ and $z_3 = \text{const.}$?

$$\mathbf{6.223} \quad T_r = E_{rs} n_s \quad (1)$$

So for the the stress across a plane $z_1 = \text{const.}$, we have $n_1 = 1$, $n_2 = 0$, $n_3 = 0$ and so

$$T_r (z_1 = \text{const.}) = \begin{pmatrix} E_{11} \\ E_{21} \\ E_{31} \end{pmatrix} \quad (2)$$

For the the stress across a plane $z_2 = \text{const.}$, we have $n_1 = 0$, $n_2 = 1$, $n_3 = 0$ and for the the stress across a plane $z_3 = \text{const.}$, we have $n_1 = 0$, $n_2 = 0$, $n_3 = 1$ and so

$$T_r (z_2 = \text{const.}) = \begin{pmatrix} E_{12} \\ E_{22} \\ E_{32} \end{pmatrix} \quad (3)$$

$$T_r (z_3 = \text{const.}) = \begin{pmatrix} E_{13} \\ E_{23} \\ E_{33} \end{pmatrix} \quad (4)$$

◆

5.14 p210 - Exercise

Show that the if **6.233** is solved for strain, so as to read

$$\mathbf{6.237} \quad e_{rs} = C_{rsmn} E_{mn}$$

then the symmetry conditions **6.234**, **6.235**, and **6.236** imply similar conditions on C_{rsmn} . (The tensor C_{rsmn} is the second elasticity tensor).

a) $C_{rsnm} = C_{rsmn}$ and $C_{srnm} = C_{rsmn}$

This is a direct consequence of the symmetries $E_{nm} = E_{mn}$ and $e_{nm} = e_{mn}$.

E.g.:

$$e_{nm} = e_{mn} \tag{1}$$

$$\Leftrightarrow C_{nmrs} E_{rs} = C_{mnrs} E_{rs} \tag{2}$$

$$\Rightarrow C_{nmrs} = C_{mnrs} \tag{3}$$

b) $C_{rsnm} = C_{mnrs}$

We simplify the notation by using 'compactified' indices (e.g.):

$$e_a = C_{ab} E_b \quad \Leftrightarrow \quad e_{rs} = C_{rsmn} E_{mn}$$

Let's form the invariant $E_a e_a$, then :

$$E_a e_a = c_{au} e_u C_{av} E_v \tag{4}$$

$$= c_{ua} e_a C_{uv} E_v \quad (\text{renaming dummy indices}) \tag{5}$$

$$= C_{uv} E_u E_v \tag{6}$$

$$= C_{vu} E_u E_v \quad (\text{renaming dummy indices}) \tag{7}$$

From (6) and (7) we can conclude

$$C_{vu} = C_{uv}$$



5.15 p212 - Exercise

Deduce from **6.250** that if an isotropic elastic body is in equilibrium under no body forces, then the expansion θ is an harmonic function ($\Delta\theta = 0$)

$$\mathbf{6.250} : \quad \rho f_r = \rho X_r + (\lambda + \mu) \theta_{,r} + \mu \Delta u_r$$

In equilibrium under no body forces means $f_r = 0$ and $X_r = 0$. So,

$$(\lambda + \mu) \theta_{,r} + \mu \Delta u_r = 0 \tag{1}$$

$$\partial_r \Rightarrow (\lambda + \mu) \underbrace{\theta_{,rr}}_{=\Delta\theta} + \mu \underbrace{(\Delta u_r)_{,r}}_{=\Delta u_{r,r}} = 0 \tag{2}$$

$$u_{r,r} = \theta \Rightarrow (\lambda + \mu) \Delta\theta + \mu \Delta\theta = 0 \tag{3}$$

$$\Rightarrow \Delta\theta = 0 \tag{4}$$



5.16 p213 - Exercise

Express the equations of motion **6.250** in curvilinear coordinates.

$$\mathbf{6.250} : \quad \rho f_r = \rho X_r + (\lambda + \mu) \theta_{,r} + \mu \Delta u_r$$

We start from **6.252** : $\rho f^r = \rho X^r + E^{rs}_{|s}$

$$\rho f^r = \rho X^r + E^{rs}_{|s} \quad (1)$$

$$\mathbf{6.245} : \Rightarrow E^{rs} = \lambda \delta_{rs} \theta + 2\mu e^{rs} \quad (2)$$

$$\Rightarrow \rho f^r = \rho X^r + \lambda \delta_{rs} \theta_{|s} + 2\mu e^{rs}_{|s} \quad (3)$$

$$\Leftrightarrow \rho f^r = \rho X^r + \lambda \theta_{,r} + 2\mu e^{rs}_{|s} \quad (4)$$

$$\mathbf{6.245} : \quad e^{rs} = \frac{1}{2} (u^r_{|s} + u^s_{|r}) \quad (5)$$

$$\Leftrightarrow \rho f^r = \rho X^r + \lambda \theta_{,r} + 2\mu \frac{1}{2} (u^r_{|ss} + u^s_{|rs}) \quad (6)$$

$$\mathbf{6.246} : \quad \theta = e^{nn} = \frac{1}{2} (u^n_{|n} + u^n_{|n}) = u^n_{|n} \quad (7)$$

$$(6) \Rightarrow \rho f^r = \rho X^r + \lambda \theta_{,r} + \mu (u^r_{|ss} + \theta_{|r}) \quad (8)$$

$$\Rightarrow \rho f^r = \rho X^r + (\lambda + \mu) \theta_{,r} + \mu u^r_{|ss} \quad (9)$$

So,

$$f^r = \rho X^r + (\lambda + \mu) \theta_{,r} + \mu \Delta u^r$$

where we define the Laplacian differential operator as

$$\Delta(\cdot) \stackrel{\text{def}}{=} (\cdot)_{|nn}$$



5.17 p215 - Exercise

Verify that $E_r = z_r$, $H_r = 0$ satisfy the wave equation but not Maxwell's equations

$$\mathbf{6.306} : \quad \frac{1}{c^2} \frac{\partial^2 E_r}{\partial t^2} - E_{r,mn} = 0$$

$$\mathbf{6.307} : \quad \frac{1}{c^2} \frac{\partial^2 H_r}{\partial t^2} - H_{r,mn} = 0$$

Obviously, **6.307** is trivial as $H_r = 0$ is a constant $= 0$, and so are the derivatives.

For **6.306**, $\frac{\partial^2 E_r}{\partial t^2} = 0$ as E_r is no function of time.

So, the defined field satisfy the wave equation.

$$\left\{ \begin{array}{ll} \mathbf{6.301} : & \frac{1}{c} \frac{\partial E_r}{\partial t} = \epsilon_{rmn} H_{n,m}, \quad \frac{1}{c} \frac{\partial H_r}{\partial t} = -\epsilon_{rmn} E_{n,m} \\ \mathbf{6.302} : & E_{n,n} = 0, \quad H_{n,n} = 0 \end{array} \right. \quad (1)$$

The first equation of **6.302** is not satisfied as $E_{n,n} = N$ with N the space dimension.



5.18 p220 - Exercise

Prove a similar statement for the electric and magnetic vectors of the complementary electromagnetic field.

If we take the complex conjugate of **6.324** and subtract, we obtain after multiplying by i :

$$E_r^{**} = -\epsilon_{rmn} H_n^{**} V_{,m}, \quad H_r^{**} = \epsilon_{rmn} E_n^{**} V_{,m}, \quad (1)$$

Hence, the vectors $V_{,r}, E_r^{**}$ and H_r^{**} form a right-handed orthogonal triad, and we obtain the relation

$$E_r^{**} E_r^{**} = H_n^{**} H_n^{**} \quad (2)$$



5.19 p221 - Clarification

Some thoughts about polarization

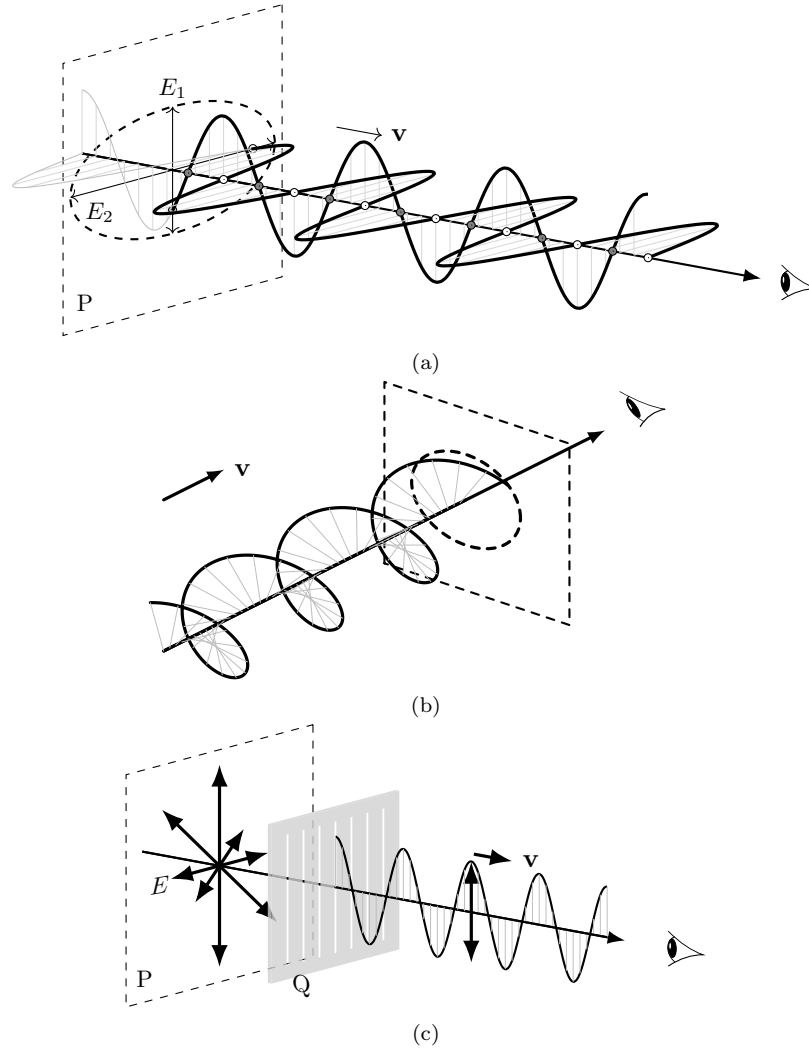


Figure 5.3: Polarization of light

In the above figures, only the electric field is represented (the magnetic field has to be imagined perpendicular to the \mathbf{E}_r vector).

In figure (a) we see an elliptical polarization which occurs when the EMW can be split into two perpendicular components. When $|\overline{E_1}| = |\overline{E_2}|$, one can speak about circular polarization. Figure (b) gives a view at a certain time t of the result of $\overline{E_1} + \overline{E_2}$. In figure (c) an observer 'sees' in the phase wave situated at P , an unpolarized EMV. After passing a linear polarizing material at Q the observer will 'see' the EMV oscillating only in the vertical plane along \mathbf{v}

◆

5.20 p221 - Exercise

What conditions must be imposed on the fixed complex vectors $E_r^{(0)}$ and $H_r^{(0)}$ in order that the wave may be plane-polarized

As stated a plane-polarized wave will have its vectors E_r^* and E_r^{**} have the same directions and moreover the E_r^* vector maintains a fixed directions.

This means that E_r^* can be written as $E_r^* = \alpha(z, t) \mathcal{E}_r$ and $E_r^{**} = \beta(z, t) \mathcal{E}_r$ with α, β real valued functions and \mathcal{E}_r a constant. Note that from the definition of E_r^* and E_r^{**} we have

$$E_r = E_r^* + iE_r^{**} \quad (1)$$

and

$$6.330 \quad \left\{ \begin{array}{l} \frac{\partial E_r^*}{\partial t} = -\frac{2\pi c}{\lambda} E_r^{**} \\ \frac{\partial E_r^{**}}{\partial t} = \frac{2\pi c}{\lambda} E_r^* \end{array} \right. \quad (2)$$

$$\Rightarrow \left\{ \begin{array}{l} \frac{\partial \alpha}{\partial t} = -\frac{2\pi c}{\lambda} \beta \\ \frac{\partial \beta}{\partial t} = \frac{2\pi c}{\lambda} \alpha \end{array} \right. \quad (3)$$

$$\Rightarrow \left\{ \begin{array}{l} \frac{\partial^2 \alpha}{\partial t^2} = -\left(\frac{2\pi c}{\lambda}\right)^2 \alpha \\ \frac{\partial^2 \beta}{\partial t^2} = -\left(\frac{2\pi c}{\lambda}\right)^2 \beta \end{array} \right. \quad (4)$$

$$\Rightarrow \left\{ \begin{array}{l} \alpha = A(z) \cos \frac{2\pi c}{\lambda} t + B(z) \sin \frac{2\pi c}{\lambda} t \\ \beta = C(z) \cos \frac{2\pi c}{\lambda} t + D(z) \sin \frac{2\pi c}{\lambda} t \end{array} \right. \quad (5)$$

$$\Rightarrow \frac{E_r}{\mathcal{E}_r} = A \cos \frac{2\pi c}{\lambda} t + B \sin \frac{2\pi c}{\lambda} t + i \left(C(z) \cos \frac{2\pi c}{\lambda} t + D(z) \sin \frac{2\pi c}{\lambda} t \right) \quad (6)$$

With $A, B, C, D : \mathbb{R}^3 \rightarrow \mathbb{R}$.

Let's write $E_r^{(0)}$ as $E_r^{(0)} = a + ib$ with a, b real valued functions depending on the position only.

Then, **6.308** can be rewritten as

$$E_r = (a + ib) (\cos S + i \sin S) \quad (7)$$

$$= a \cos S - b \sin S + i (b \cos S + a \sin S) \quad (8)$$

We have, with $S = \frac{2\pi V}{\lambda} - \frac{2\pi c}{\lambda}t$

$$\begin{cases} \cos S = \cos \frac{2\pi V}{\lambda} \cos \frac{2\pi c}{\lambda}t + \sin \frac{2\pi V}{\lambda} \sin \frac{2\pi c}{\lambda}t \\ \sin S = \sin \frac{2\pi V}{\lambda} \cos \frac{2\pi c}{\lambda}t - \cos \frac{2\pi V}{\lambda} \sin \frac{2\pi c}{\lambda}t \end{cases} \quad (9)$$

$$(8) \Rightarrow E_r = \begin{cases} a \cos \frac{2\pi V}{\lambda} \cos \frac{2\pi c}{\lambda}t + a \sin \frac{2\pi V}{\lambda} \sin \frac{2\pi c}{\lambda}t + b \cos \frac{2\pi V}{\lambda} \sin \frac{2\pi c}{\lambda}t - b \sin \frac{2\pi V}{\lambda} \cos \frac{2\pi c}{\lambda}t \\ + i \left(b \cos \frac{2\pi V}{\lambda} \cos \frac{2\pi c}{\lambda}t + b \sin \frac{2\pi V}{\lambda} \sin \frac{2\pi c}{\lambda}t - a \cos \frac{2\pi V}{\lambda} \sin \frac{2\pi c}{\lambda}t + a \sin \frac{2\pi V}{\lambda} \cos \frac{2\pi c}{\lambda}t \right) \end{cases} \quad (10)$$

$$= \begin{cases} \left(a \cos \frac{2\pi V}{\lambda} - b \sin \frac{2\pi V}{\lambda} \right) \cos \frac{2\pi c}{\lambda}t + \left(a \sin \frac{2\pi V}{\lambda} + b \cos \frac{2\pi V}{\lambda} \right) \sin \frac{2\pi c}{\lambda}t \\ + i \left[\left(b \cos \frac{2\pi V}{\lambda} + a \sin \frac{2\pi V}{\lambda} \right) \cos \frac{2\pi c}{\lambda}t + \left(b \sin \frac{2\pi V}{\lambda} - a \cos \frac{2\pi V}{\lambda} \right) \sin \frac{2\pi c}{\lambda}t \right] \end{cases} \quad (11)$$

Let's now compare equations (6) and (11)

$$E_r = A\mathcal{E}_r \cos \frac{2\pi c}{\lambda}t + B\mathcal{E}_r \sin \frac{2\pi c}{\lambda}t + i \left(C\mathcal{E}_r \cos \frac{2\pi c}{\lambda}t + D\mathcal{E}_r \sin \frac{2\pi c}{\lambda}t \right) \quad (12)$$

$$E_r = \begin{cases} \left(a \cos \frac{2\pi V}{\lambda} - b \sin \frac{2\pi V}{\lambda} \right) \cos \frac{2\pi c}{\lambda}t + \left(a \sin \frac{2\pi V}{\lambda} + b \cos \frac{2\pi V}{\lambda} \right) \sin \frac{2\pi c}{\lambda}t \\ + i \left[\left(a \sin \frac{2\pi V}{\lambda} + b \cos \frac{2\pi V}{\lambda} \right) \cos \frac{2\pi c}{\lambda}t - \left(a \cos \frac{2\pi V}{\lambda} - b \sin \frac{2\pi V}{\lambda} \right) \sin \frac{2\pi c}{\lambda}t \right] \end{cases} \quad (13)$$

We see that

$$A\mathcal{E}_r = a \cos \frac{2\pi V}{\lambda} - b \sin \frac{2\pi V}{\lambda} \quad (14)$$

$$B\mathcal{E}_r = a \sin \frac{2\pi V}{\lambda} + b \cos \frac{2\pi V}{\lambda} \quad (15)$$

$$C = B \quad (16)$$

$$D = -A \quad (17)$$

$$(14), (15) \Rightarrow \begin{cases} a = A\mathcal{E}_r \cos \frac{2\pi V}{\lambda} + B\mathcal{E}_r \sin \frac{2\pi V}{\lambda} \\ b = -A\mathcal{E}_r \sin \frac{2\pi V}{\lambda} + B\mathcal{E}_r \cos \frac{2\pi V}{\lambda} \end{cases} \quad (18)$$

$$\Rightarrow E_r^{(0)} = a + ib \quad (19)$$

$$= \mathcal{E}_r (A(z) + iB(z)) e^{-\frac{2\pi V}{\lambda}} \quad (20)$$

So, the direction of $E_r^{(0)}$ does not change as $\frac{E_r^{(0)}}{E_s^{(0)}} = \frac{\mathcal{E}_r}{\mathcal{E}_s}$ and the magnitude varies with the position but in such a way that the effect of V is annihilated.



5.21 p223 - Clarification

Interrelationship between the identities **6.337** to **6.340**

$$\mathbf{6.337} \quad \frac{1}{c^2} \frac{\partial^2 \phi_r}{\partial t^2} + \frac{1}{c} \frac{\partial \psi_{,r}}{\partial t} = \phi_{r,mm} - \phi_{m,mr} \quad (1)$$

$$\mathbf{6.338} \quad \frac{1}{c} \frac{\partial}{\partial t} \phi_{m,m} + \psi_{,mm} = 0 \quad (2)$$

$$\mathbf{6.339(a)} \quad \frac{1}{c^2} \frac{\partial^2 \phi_r}{\partial t^2} - \phi_{r,mm} = 0 \quad (3)$$

$$\mathbf{6.339(b)} \quad \frac{1}{c^2} \frac{\partial^2 \psi}{\partial t^2} - \psi_{,mm} = 0 \quad (4)$$

$$\mathbf{6.340} \quad \frac{1}{c} \frac{\partial \psi}{\partial t} + \phi_{m,m} = 0 \quad (5)$$

then

$$(3) \text{ in } (1) \quad \frac{1}{c} \frac{\partial \psi_{,r}}{\partial t} = -\phi_{m,mr} \quad (6)$$

$$\frac{\partial(5)}{\partial z_r} \quad \frac{1}{c} \frac{\partial \psi_{,r}}{\partial t} + \phi_{m,mr} = 0 \quad \Leftrightarrow \quad (6) \quad (7)$$

What about (4) ?

$$(4) \text{ in } (2) \quad \frac{1}{c} \frac{\partial}{\partial t} \phi_{m,m} = -\frac{1}{c^2} \frac{\partial^2 \psi}{\partial t^2} \quad (8)$$

$$\int_t (8) \Rightarrow \frac{1}{c} \frac{\partial \psi}{\partial t} + \phi_{m,m} = C \quad (9)$$

In (9), C is a function, constant in t . Imposing $C = 0$ gives still a valid solution and is equivalent with (5).



5.22 p223 - Clarification

$$\mathbf{6.342} \quad \frac{1}{c^2} \frac{\partial^2 \Pi_r}{\partial t^2} - \Pi_{r,mm} = 0$$

$$\mathbf{6.341(a)} \quad \mathbf{E}_n = \Pi_{m,mn} - \frac{1}{c^2} \frac{\partial^2 \Pi_n}{\partial t^2} \quad (1)$$

$$\mathbf{6.341(b)} \quad \mathbf{H}_n = \frac{1}{c} \epsilon_{npq} \frac{\partial}{\partial t} \Pi_{q,p} \quad (2)$$

We first check, under which conditions (1) and (2) satisfy the Maxwell equations

$$\left\{ \begin{array}{ll} \mathbf{6.301(a),(b)} & E_{m,m} = 0, \quad H_{m,m} = 0 \\ \mathbf{6.302(a)} & \frac{1}{c} \frac{\partial E_r}{\partial t} = \epsilon_{rmn} H_{n,m} \\ \mathbf{6.302(b)} & \frac{1}{c} \frac{\partial H_r}{\partial t} = -\epsilon_{rmn} E_{n,m} \end{array} \right. \quad (3)$$

with the wave equations:

$$\left\{ \begin{array}{ll} \mathbf{6.306} & \frac{1}{c^2} \frac{\partial^2 E_r}{\partial t^2} - E_{r,mm} = 0 \\ \mathbf{6.307} & \frac{1}{c^2} \frac{\partial^2 H_r}{\partial t^2} - H_{r,mm} = 0 \end{array} \right. \quad (4)$$

We have for **6.301(b)**:

$$(2)_{,n} \quad H_{n,n} = \frac{1}{c} \epsilon_{npq} \frac{\partial \Pi_{q,pn}}{\partial t} \quad (5)$$

$$= 0 \quad (\Pi_{q,pn} = \Pi_{q,np} \text{ and } \epsilon_{npq} = -\epsilon_{pnq}) \quad (6)$$

So, **6.301(b)** is satisfied.

For **6.302(b)** we have:

$$\mathbf{6.302(b)} \quad \frac{1}{c} \frac{\partial H_r}{\partial t} = -\epsilon_{rmn} E_{n,m} \quad (7)$$

$$(2)_{,t} \Rightarrow \frac{1}{c} \epsilon_{npq} \frac{\partial^2}{\partial t^2} \Pi_{q,p} = -\epsilon_{rmn} E_{n,m} \quad (8)$$

$$(1) \text{ in } (8) \Rightarrow \frac{1}{c} \epsilon_{npq} \frac{\partial^2}{\partial t^2} \Pi_{q,p} = -\underbrace{\epsilon_{rmn} \Pi_{q,qnm}}_{=0} + \epsilon_{rmn} \frac{1}{c^2} \frac{\partial^2 \Pi_{n,m}}{\partial t^2} \quad (9)$$

$$\Rightarrow \frac{1}{c} \epsilon_{npq} \frac{\partial^2}{\partial t^2} \Pi_{q,p} = \epsilon_{rmn} \frac{1}{c^2} \frac{\partial^2 \Pi_{n,m}}{\partial t^2} \quad (10)$$

So, **6.302(b)** is satisfied.

We still have to prove that the expression (1) and (2) are consistent with 6.301(a) and 6.302(a)

also for **6.301(a)**:

$$(1)_{,n} \quad E_{n,n} = \Pi_{m,mnn} - \frac{1}{c^2} \frac{\partial^2 \Pi_{n,n}}{\partial t^2} \quad (11)$$

and for **6.302(a)**:

$$6.302(a) \quad \frac{1}{c} \frac{\partial E_r}{\partial t} = \epsilon_{rmn} H_{n,m} \quad (12)$$

$$(2) \Rightarrow \quad = \epsilon_{rmn} \frac{1}{c} \epsilon_{npq} \frac{\partial}{\partial t} \Pi_{q,pm} \quad (13)$$

$$\Rightarrow \quad \frac{\partial E_r}{\partial t} = \epsilon_{rmn} \epsilon_{npq} \frac{\partial}{\partial t} \Pi_{q,pm} \quad (14)$$

$$= (\delta_{rp} \delta_{mq} - \delta_{rq} \delta_{mp}) \frac{\partial}{\partial t} \Pi_{q,pm} \quad (15)$$

$$= \partial_t \Pi_{m,rm} - \partial_t \Pi_{r,mm} \quad (16)$$

Let's impose the condition on Π_n :

$$\mathbf{6.342} \quad \Pi_{r,mm} = \frac{1}{c^2} \frac{\partial^2 \Pi_r}{\partial t^2} \quad (17)$$

From (1) we have

$$\frac{1}{c^2} \frac{\partial^2 \Pi_n}{\partial t^2} = \Pi_{m,mn} - E_n \quad (18)$$

$$(17) \text{ becomes } \quad \Pi_{r,mm} = \Pi_{m,mn} - E_n \quad (19)$$

$$\Rightarrow \quad E_n = \Pi_{m,mn} - \Pi_{r,mm} \quad (20)$$

$$\Rightarrow \quad \partial_t E_n = \partial_t \Pi_{m,mn} - \partial_t \Pi_{r,mm} \quad (21)$$

Which is consistent with **6.302(a)** following (16).

For **6.301(a)** we have

$$(16)_{,n} \Rightarrow \quad \frac{1}{c^2} \frac{\partial^2 \Pi_{n,n}}{\partial t^2} = \Pi_{n,mmn} \quad (22)$$

$$(11) \Rightarrow \quad E_{n,n} = \Pi_{m,mnn} - \Pi_{n,mmn} \quad (23)$$

$$= 0 \quad (24)$$

Which is consistent with **6.301(a)**



5.23 p226 - Clarification

$$\mathbf{6.361} \quad \Pi_r^{(0)}(z) = \int_{V_\zeta} P_r(\zeta) F(z, \zeta) dV_\zeta$$

The reason why we can find a solution in the form **6.361** is because the condition **6.358** : $\Pi_{r,mm}^{(0)} + k^2 \Pi_r^{(0)} = 0$ is a linear homogeneous differential equation. So any linear combination of solutions of this equation will also be a solution:

Be

$$\Pi_r^{(0)} = \sum_{n=1}^N C_n \Pi_r^{n(0)} \quad (1)$$

where the $\Pi_r^{n(0)}$ satisfy the condition $\Pi_{r,mm}^{n(0)} + k^2 \Pi_r^{n(0)} = 0$ and are evaluated at the same point z_r but at different ζ_n .

This is the situation as illustrated in the figure (a) below.

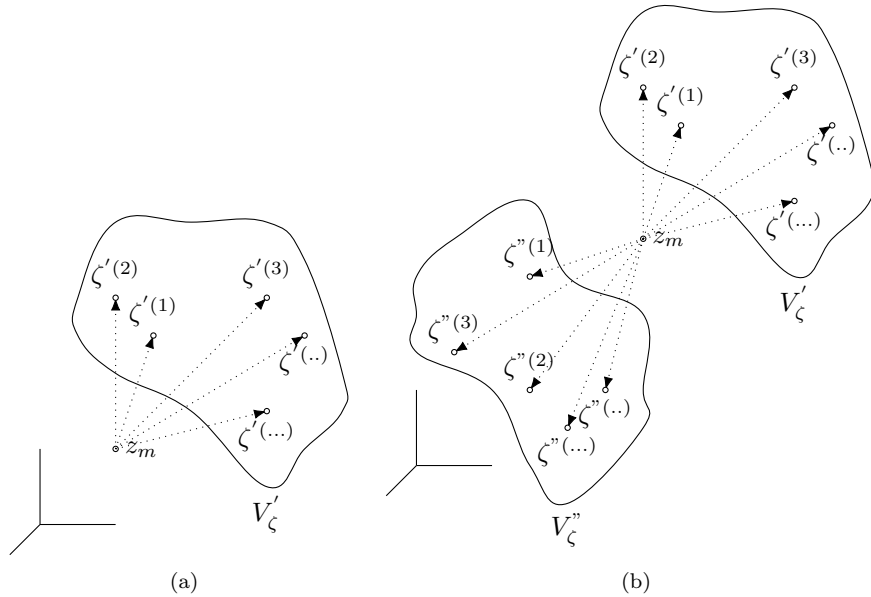


Figure 5.4: Integral form of Hertz vectors

If we take more and more points ζ_r and take the C_k as a weight factor, then in the limit, we get $\Pi_r^{(0)}(z) = \int_{V_\zeta} P_r(\zeta) F(z, \zeta) dV_\zeta$ where $P_r(\zeta)$ is a kind of density vector field. On page 227, it is mentioned that the vector field $P_r(\zeta)$ does not need to be continuous. This situation is illustrated in the figure (b) where $V_\zeta = V'_\zeta \oplus V''_\zeta$



5.24 p227 - Exercise

Show that Maxwell's equation in the form **6.356** are satisfied by

$$\begin{aligned} E_r^{(0)} &= ik\epsilon_{rpq} \int_{V_\zeta} Q_q(\zeta) F_{,p} dV_\zeta \\ \mathbf{6.363} \quad H_r^{(0)} &= \int_{V_\zeta} Q_m(\zeta) (F_{,mr} + k^2 F \delta_{mr}) dV_\zeta \end{aligned}$$

where $Q_r(\zeta)$ is an arbitrary vector field, and F is as in **6.344**

Let's first look at this with a discrete point and define

$$E_r^{(0)} = ik\epsilon_{rpq} \Pi_{q,p}^{(0)} \quad (1)$$

$$H_r^{(0)} = \Pi_{m,mr}^{(0)} + k^2 \Pi_r^{(0)} \quad (2)$$

We check whether that Maxwell's equation in the form **6.356** are satisfied:

$$-ikE_r^{(0)} = \epsilon_{rmn} H_{n,m}^{(0)} \quad (3)$$

$$(1) \text{ and } (2) \Rightarrow -ikik\epsilon_{rpq} \Pi_{q,p}^{(0)} = \underbrace{\epsilon_{rmn} \Pi_{q,qmn}^{(0)}}_{=0} + \epsilon_{rmn} k^2 \Pi_{n,m}^{(0)} \quad (4)$$

$$\Rightarrow k^2 \epsilon_{rpq} \Pi_{q,p}^{(0)} = \epsilon_{rmn} k^2 \Pi_{n,m}^{(0)} \quad (5)$$

So the first Maxwell equation is satisfied.

For the second

$$ikH_r^{(0)} = \epsilon_{rmn} E_{n,m}^{(0)} \quad (6)$$

$$(1) \text{ and } (2) \Rightarrow ik\Pi_{m,mr}^{(0)} + ik^3 \Pi_r^{(0)} = \epsilon_{rmn} ik\epsilon_{npq} \Pi_{q,p}^{(0)} \quad (7)$$

$$\Rightarrow \Pi_{m,mr}^{(0)} + k^2 \Pi_r^{(0)} = (\delta_{rp} \delta_{mq} - \delta_{rq} \delta_{mp}) \Pi_{q,p}^{(0)} \quad (8)$$

$$\Rightarrow \Pi_{m,mr}^{(0)} + k^2 \Pi_r^{(0)} = \Pi_{m,mr}^{(0)} - \Pi_{r,mm}^{(0)} \quad (9)$$

$$\Rightarrow \Pi_{r,mm}^{(0)} + k^2 \Pi_r^{(0)} = \Pi_{m,mr}^{(0)} - \Pi_{m,mr}^{(0)} = 0 \quad (10)$$

Conclusion, (1) and (2) are valid expressions of a EMW provided that the condition (10) is respected.

The rest of the reasoning is identical as for the previous form for $E_r^{(0)}$ and $H_r^{(0)}$ when we take a linear combination of $\Pi_r^{(0)}$, each satisfying (10) and taking the limit on volume V_ζ while expressing $\Pi_r^{(0)}$ as $Q_r(\zeta) F(z, \zeta)$.



5.25 p228 - Exercise

Write out Maxwell's equations in terms of a magnetic vector and a skew-symmetric electric tensor.

Let's define

$$E_{rm} = \epsilon_{rmn} E_n \quad (1)$$

$$\Rightarrow E_r = \frac{1}{2} \epsilon_{rmn} E_{mn} \quad (2)$$

Maxwell's equation :

$$\left\{ \begin{array}{ll} 6.301(a),(b) & E_{m,m} = 0, \quad H_{m,m} = 0 \\ 6.302(a) & \frac{1}{c} \frac{\partial E_r}{\partial t} = \epsilon_{rmn} H_{n,m} \\ 6.302(b) & \frac{1}{c} \frac{\partial H_r}{\partial t} = -\epsilon_{rmn} E_{n,m} \end{array} \right. \quad (3)$$

6.302(a):

$$6.302(a) \times \epsilon_{rmn} \Rightarrow \frac{1}{c} \frac{\partial E_{rm}}{\partial t} = -\epsilon_{rmn} \epsilon_{npq} H_{q,p} \quad (4)$$

$$= (\delta_{mp} \delta_{rq} - \delta_{mq} \delta_{rp}) H_{q,p} \quad (5)$$

$$= H_{r,m} - H_{m,r} \quad (6)$$

So,

$$\frac{\partial \mathbf{E}_{\mathbf{r}\mathbf{m}}}{\partial \mathbf{t}} = \mathbf{H}_{\mathbf{r},\mathbf{m}} - \mathbf{H}_{\mathbf{m},\mathbf{r}}$$

6.302(b):

$$(2) \text{ in } 6.302(b) \Rightarrow \frac{1}{c} \frac{\partial H_r}{\partial t} = \frac{1}{2} \epsilon_{rmn} \epsilon_{npq} E_{pq,m} \quad (7)$$

$$= \frac{1}{2} (\delta_{rp} \delta_{mq} - \delta_{rq} \delta_{pm}) E_{pq,m} \quad (8)$$

$$= \frac{1}{2} (E_{rm,m} - E_{mr,m}) \quad (9)$$

$$= E_{rm,m} \quad (E_{rm} \text{ is skew-symmetric}) \quad (10)$$

So,

$$\frac{1}{c} \frac{\partial \mathbf{H}_{\mathbf{r}}}{\partial \mathbf{t}} = \mathbf{E}_{\mathbf{r}\mathbf{m},\mathbf{m}}$$

6.301(a):

$$(2) \text{ in } 6.301(a) \quad \Rightarrow \quad \epsilon_{rmn} E_{mn,r} = 0 \quad (11)$$

As this equation is homogeneous, we can permute the indices in $E_{mn,r}$ and write $\epsilon_{rmn} E_{rn,m} = 0$ and $\epsilon_{rmn} E_{mr,n} = 0$.

Adding this three equation together we get

$$\mathbf{E}_{mn,r} + \mathbf{E}_{rn,m} + \mathbf{E}_{mr,n} = \mathbf{0}$$

6.302(b):

As in this case, nothing changes for H_r we have

$$\mathbf{H}_{n,n} = \mathbf{0}$$



5.26 p229 - Clarification

$$\mathbf{6.371} \quad F_{\alpha\beta} = H_{\alpha\beta}, \quad -F_{4\alpha} = E_{\alpha}, \quad F_{44} = 0$$

$$\mathbf{6.374} \quad g_{\alpha\beta} = a_{\alpha\beta}, \quad g_{\alpha 4} = 0, \quad g_{44} = -1$$

For clarity this give in matrix form

$$(F_{mn}) = \begin{pmatrix} 0 & H_3 & H_2 & E_1 \\ -H_3 & 0 & H_1 & E_2 \\ H_2 & -H_1 & 0 & E_3 \\ -E_1 & -E_2 & -E_3 & 0 \end{pmatrix} \quad (1)$$

$$(g_{mn}) = \begin{pmatrix} a_{11} & a_{12} & a_{13} & 0 \\ a_{12} & a_{22} & a_{23} & 0 \\ a_{13} & a_{23} & a_{33} & 0 \\ 0 & 0 & 0 & -1 \end{pmatrix} \quad (2)$$



5.27 p231 - Exercise

Show that with homogeneous coordinates $z - r$ (z_1, z_2, z_3 being rectangular Cartesians in space and $z_4 = ict = ix^4$) Maxwell's equations read

$$F_{rm,n} + F_{mn,r} + F_{nr,m} = 0, \quad F_{rm,m} = 0$$

Write out the components of F_{mn} in terms of the real electric and magnetic vectors, noting which components are real and which are imaginary.

We use the same convention as in the book: Greek indices are restricted to the space manifold. Extending this manifold to a 4 dimensional manifold, Latin suffixes will be used. We have **6.369**:

$$\left\{ \begin{array}{l} \text{(a)} \quad \frac{1}{c} \frac{\partial E_r}{\partial t} = a^{mn} H_{rm|n} \\ \text{(b)} \quad \frac{1}{c} \frac{\partial H_{rm}}{\partial t} = E_{r,m} - E_{m,r} \\ \text{(c)} \quad a^{mn} E_{n|m} = 0 \\ \text{(d)} \quad H_{rm,n} + H_{mn,r} + H_{nr,m} = 0 \end{array} \right. \quad (1)$$

We rewrite (1):

$$\left\{ \begin{array}{l} \text{(a)} \quad \frac{\partial E_\alpha}{\partial(ict)} = -a^{\beta\gamma} H_{\alpha\beta|\gamma} \\ \text{(b)} \quad i \frac{\partial H_{\alpha\beta}}{\partial(ict)} = E_{\alpha,\beta} - E_{\beta,\alpha} \\ \text{(c)} \quad a^{\alpha\beta} E_{\beta|\alpha} = 0 \\ \text{(d)} \quad H_{\alpha\beta,\gamma} + H_{\beta\gamma,\alpha} + H_{\gamma\alpha,\beta} = 0 \end{array} \right. \quad (2)$$

instead of **6.371** let's define:

$$F_{\alpha\beta} = H_{\alpha\beta}, \quad F_{\alpha 4} = -F_{4\alpha} = -iE_\alpha, \quad F_{44} = 0 \quad (3)$$

$$\Rightarrow \quad E_\alpha = iF_{\alpha 4} = -iF_{4\alpha} \quad (4)$$

Using (4), (2) becomes

$$\left\{ \begin{array}{ll} \text{(a)} & -\frac{\partial F_{\alpha 4}}{\partial(ict)} = a^{\beta\gamma} F_{\alpha\beta|\gamma} \\ \text{(b)} & i\frac{\partial F_{\alpha\beta}}{\partial(ict)} = iF_{\alpha 4,\beta} - iF_{\beta 4,\alpha} \\ \text{(c)} & a^{\alpha\beta} F_{\beta 4,\alpha} = 0 \\ \text{(d)} & F_{\alpha\beta,\gamma} + F_{\beta\gamma,\alpha} + F_{\gamma\alpha,\beta} = 0 \end{array} \right. \quad (5)$$

For homogeneous coordinates we have $a^{\alpha\gamma} = \delta_{\alpha\gamma}$ and $a^{\alpha 4} = 0$ so:

$$\left\{ \begin{array}{ll} \text{(a)} & F_{\alpha 4,4} = -F_{\alpha\beta|\beta} \\ \text{(b)} & F_{\alpha\beta,4} = F_{\alpha 4,\beta} - F_{\beta 4,\alpha} \\ \text{(c)} & F_{\beta 4,\beta} = 0 \\ \text{(d)} & F_{\alpha\beta,\gamma} + F_{\beta\gamma,\alpha} + F_{\gamma\alpha,\beta} = 0 \end{array} \right. \quad (6)$$

Let's look what happens when we extend the range α, β, γ to 4. First let's extend γ to 4. The left part of equation (6d) can be written as

$$\underbrace{F_{\alpha\beta,\gamma} + F_{\beta\gamma,\alpha} + F_{\gamma\alpha,\beta}}_{=0} + F_{\alpha\beta,4} + F_{\beta 4,\alpha} + F_{4\alpha,\beta} \quad (7)$$

Consider

$$P = F_{\alpha\beta,4} + F_{\beta 4,\alpha} + F_{4\alpha,\beta} \quad (8)$$

Let's extend α to 4:

$$P' = F_{4\beta,4} + F_{\beta 4,4} + \underbrace{F_{44,\beta}}_{=0} \quad (9)$$

$$= \underbrace{F_{4\beta,4} + F_{\beta 4,4}}_{=0} \quad (F_{mn} \text{ is skew-symmetric}) \quad (10)$$

Extend β to 4:

$$P'' = F_{44,4} + F_{44,4} + F_{44,4} \quad (11)$$

$$= 0 \quad (F_{mn} \text{ is skew-symmetric}) \quad (12)$$

This means that expression (7) can be written as

$$F_{rm,n} + F_{mn,r} + F_{nr,m} = \underbrace{F_{\alpha\beta,\gamma} + F_{\beta\gamma,\alpha} + F_{\gamma\alpha,\beta}}_{=0} + P + \underbrace{P' + P''}_{=0}$$

So, we only have to prove that $P = F_{\alpha\beta,4} + F_{\beta4,\alpha} + F_{4\alpha,\beta} = 0$.

From (6b) we get:

$$P = F_{\alpha\beta,4} + F_{\beta4,\alpha} + F_{4\alpha,\beta} \quad (13)$$

$$= F_{\alpha4,\beta} - F_{\beta4,\alpha} + F_{\beta4,\alpha} - F_{\alpha4,\beta} \quad (14)$$

$$= 0 \quad (15)$$

We get so by extending the indexes to 4: ,

$$F_{rm,n} + F_{mn,r} + F_{nr,m} = 0 \quad (16)$$

Consider now equation (6c) and extend the suffixes from 3 to 4.

What is the value of the following expression?

$$Q = F_{4m,m} = \underbrace{F_{4\beta,\beta}}_{=0 \text{ (see 6d)}} + F_{44,4} \quad (17)$$

Obviously, F_{mn} being skew-symmetric we have $F_{44} = 0 \Rightarrow F_{44,4} = 0 \Rightarrow Q = 0$.

From **6.378(b)** page 230 we know

$$g^{\gamma\beta} F_{\alpha\gamma|\beta} = F_{\alpha\beta|\beta} = 0 \quad (18)$$

So, considering (16), (17) and (18) we see that the Maxwell equations reduce to

$$\begin{cases} F_{rm,n} + F_{mn,r} + F_{nr,m} = 0 \\ F_{rm,m} = 0 \end{cases} \quad (19)$$

For the explicit expression of F_{mn} we get from (3) and (4):

$$F_{mn} = \begin{pmatrix} 0 & H_3 & -H_1 & -iE_1 \\ -H_3 & 0 & H_2 & -iE_2 \\ H_1 & -H_2 & 0 & -iE_3 \\ iE_1 & iE_2 & iE_3 & 0 \end{pmatrix} \quad (20)$$



5.28 p234 - Exercise 1

For a fluid in motion referred to curvilinear coordinates, the kinetic energy of the fluid in any region R is

$$T = \frac{1}{2} \int_R \rho v_r v^r dV$$

Use the equation of motion **6.147** to show that, if we follow the particles which compose R , we have

$$\frac{dT}{dt} = - \int_S p n_r v^r dS + \int_R \theta p dV + \int_R \rho v_r X^r dV$$

where S is the bounding surface to R , and n_r the unit vector normal to S and drawn outward. Show further that if, instead of following the particles, we calculate the rate of change of T for a fixed portion of space, we get the above expression with the following additional term

$$- \frac{1}{2} \int_S \rho n_r v^r v_s v^s dS$$

Let's recall that

$$\theta = v^r|_r \quad (\text{6.126 page 196.}) \quad (1)$$

and

$$\left\{ \begin{array}{ll} \text{(a)} & \frac{\partial v_r}{\partial t} + v^s v_r|_s = X_r - \rho^{-1} p_{,r} \quad \text{see (6.147)} \\ \text{(b)} & \frac{\partial v^r}{\partial t} + v_s v^r|_s = X^r - \rho^{-1} a^{rm} p_{,m} \quad \text{see exercise page 201} \end{array} \right. \quad (2)$$

First let us note that, for the first part of the question, we move with the particles which means that for the considered region the mass contained in this region will remain unchanged and hence ρdV can be considered as a constant when bringing the derivation operator inside the volume integral. So,

$$T = \frac{1}{2} \int_R \rho v_r v^r dV \quad (3)$$

$$\Rightarrow \quad \frac{dT}{dt} = \frac{1}{2} \int_R \left(\frac{\delta v_r}{\delta t} v^r + \frac{\delta v_r}{\delta t} v^r \right) \rho dV \quad (4)$$

$$= \frac{1}{2} \int_R \left[(\partial_t v_r + v^s v_{r|s}) v^r + v_r (\partial_t v^r + v_s v^r_{|s}) \right] \rho dV \quad (5)$$

$$= \frac{1}{2} \int_R \left[(X_r - \rho^{-1} p_{,r}) v^r + v_r (X^r - \rho^{-1} a^{rm} p_{,m}) \right] \rho dV \quad (6)$$

$$= \frac{1}{2} \int_R \left(\underbrace{X_r v^r}_{=X^r v_r} - \rho^{-1} p_{,r} v^r + X^r v_r - \rho^{-1} a^{rm} v_r p_{,m} \right) \rho dV \quad (7)$$

$$= -\frac{1}{2} \int_R \left(p_{,r} v^r + \underbrace{a^{rm} v_r p_{,m}}_{=v^m} \right) dV + \int_R \rho X^r v_r dV \quad (8)$$

$$= - \int_R p_{,r} v^r dV + \int_R \rho X^r v_r dV \quad (9)$$

Let's look at the expression $p_{,r} v^r$ in the first integral in (9).

Obviously:

$$(p v^r)_{,r} = p_{,r} v^r + p v^r_{,r} \quad (10)$$

$$\Rightarrow \quad p_{,r} v^r = (p v^r)_{,r} - p v^r_{,r} \quad (11)$$

Let's note also that

$$(p v^r)_{|r} - p v^r_{|r} = (p v^r)_{,r} + \Gamma^r_{mr} (p v^m) - p v^r_{,r} - p \Gamma^r_{mr} v^m \quad (12)$$

$$= (p v^r)_{,r} - p v^r_{,r} \quad (13)$$

$$(11) \text{ becomes } \quad p_{,r} v^r = (p v^r)_{|r} - p v^r_{|r} \quad (14)$$

Substituting in (9):

$$\frac{dT}{dt} = - \int_R (p v^r)_{|r} dV + \int_R p v^r_{|r} dV + \int_R \rho X^r v_r dV \quad (15)$$

Using Green's theorem $\int F_r n^r dS = \int F^r_{|r} dV$, and putting $F^r = p v^r$:

$$\frac{dT}{dt} = - \int_S p \underbrace{v_r n^r}_{=v^r n_r} dS + \int_R p \underbrace{v^r_{|r}}_{=\theta} dV + \int_R \rho X^r v_r dV \quad (16)$$

giving

$$\frac{dT}{dt} = - \int_S p v^r n_r dS + \int_R p \theta dV + \int_R \rho X^r v_r dV \quad (17)$$

◇

What if we look at the rate of change of T in a fixed region?

Then ρdV can't be considered as a constant and bringing the derivative operator under the integral

will generate an additional term

$$\frac{1}{2} \int_R v_r v^r \frac{\delta \rho}{\delta t} dV \quad (18)$$

As we fix the spatial coordinates, we have $\frac{\delta \rho}{\delta t} = \partial_t \rho$ and by **6.127b** we have

$$\partial_t \rho = -(\rho v^r)_{|r} \quad (19)$$

So (18) becomes

$$(18) = -\frac{1}{2} \int_R v_s v^s (\rho v^r)_{|r} dV \quad (20)$$

Using again Green's theorem $\int F_r n^r dS = \int F^r_{|r} dV$ with $F^r = \rho v^r$ and noting that $v_s v^s$ is an invariant:

$$(18) = -\frac{1}{2} \int_S v_s v^s \rho v^r n_r dV \quad (21)$$



5.29 p235 - Exercise 2

Consider a fluid in which ρ is a function of p , moving under a conservative body force. Show that if the motion is steady, but not necessarily irrotational, then the following quantity is constant along each stream line:

$$\frac{1}{2}v_r v^r + P + U$$

(a stream line is a curve which, at each point, has the direction of the velocity vector v^r). Compare and contrast this result with **6.154**.

What is given:

$$\left\{ \begin{array}{ll} \text{(a)} & \partial_t v_r + v^s v_{r|s} = X_r - \rho^{-1} p_{,r} \quad \text{see (6.147)} \\ \text{(b)} & P_{,r} = \rho^{-1} p_{,r} \quad \text{see (6.150)} \\ \text{(c)} & X_r = -U_{,r} \quad \text{see (6.151)} \end{array} \right. \quad (1)$$

As the motion is stationary: $\partial_t v_r = 0$ and so .

$$v^s v_{r|s} + U_{,r} + P_{,r} = 0 \quad (2)$$

Let's consider a stream line given by the set of equations $x^r = x^r(u)$, where u is a parameter. Then, by definition of a streamline, and considering a steady flow, we have $\frac{dx^r}{du} = k v^r$. Considering (2) we have

$$v^s v_{r|s} + U_{,r} + P_{,r} = 0 \quad (3)$$

$$\times \frac{dx^r}{du} \quad v^s v_{r|s} \frac{dx^r}{du} + U_{,r} \frac{dx^r}{du} + P_{,r} \frac{dx^r}{du} = 0 \quad (4)$$

$$v^s v_{r|s} \frac{dx^r}{du} + \frac{dU}{du} + \frac{dP}{du} = 0 \quad (5)$$

Let's look at the first term:

$$v^s v_{r|s} \frac{dx^r}{du} = k v^s v_{r|s} v^r \quad (6)$$

$$= k v^s (a_{rm} v^m)_{|s} v^r \quad (7)$$

$$= k v^s v^m_{|s} a_{rm} v^r \quad (8)$$

$$= k v^s v^m_{|s} v_m \quad (9)$$

$$= k v^s v^r_{|s} v_r \quad (10)$$

So (5) can be equivalently written as $k v^s v_{r|s} v^r + \frac{dU}{du} + \frac{dP}{du} = 0$ and $k v^s v^r_{|s} v_r + \frac{dU}{du} + \frac{dP}{du} = 0$. Summing

these two gives

$$kv^s \left(v_r|_s v^r + v^r|_s v_r \right) + 2 \frac{dU}{du} + 2 \frac{dP}{du} = 0 \quad (11)$$

$$\Leftrightarrow kv^s (v_r v^r)|_s + 2 \frac{dU}{du} + 2 \frac{dP}{du} = 0 \quad (12)$$

$$\Leftrightarrow kv^s (v_r v^r)_{,s} + 2 \frac{dU}{du} + 2 \frac{dP}{du} = 0 \quad v_r v^r \text{ is an invariant} \quad (13)$$

$$\Leftrightarrow \frac{dx^s}{du} (v_r v^r)_{,s} + 2 \frac{dU}{du} + 2 \frac{dP}{du} = 0 \quad (14)$$

$$\Leftrightarrow \frac{d(v_r v^r)}{du} + 2 \frac{dU}{du} + 2 \frac{dP}{du} = 0 \quad (15)$$

Integrating expression (15) gives

$$\frac{1}{2} \mathbf{v}_r \mathbf{v}^r + \mathbf{U} + \mathbf{P} = \mathbf{C}$$

with C a constant along a streamline.

◇

Compare and contrast this result with **6.154** (irrotational motion).

$$-\partial_t \phi + \frac{1}{2} a^{mn} \phi_{,m} \phi_{,n} + P + U = F(t)$$

For a stationary motion ($\partial_t \phi = 0$, $F(t) = \text{constant}$) the expression reduces to

$$\frac{1}{2} \mathbf{a}^{mn} \phi_{,m} \phi_{,n} + \mathbf{P} + \mathbf{U} = \mathbf{C}$$

Replacing in the general expression $\frac{1}{2} v_r v^r + U + P = C$, $v_r v^r$ by $v_r = -\phi_{,r}$ and $v^r = -a^{rm} \phi_{,m}$ gives obviously $\frac{1}{2} a^{mn} \phi_{,m} \phi_{,n} + P + U = C$.

◆

5.30 p235 - Exercise 3

For the general motion of the fluid described in Exercise 2, prove that

$$\frac{d}{dt} \int_C v_r dx^r = 0$$

where the integral is taken round any closed curve, and $\frac{d}{dt}$ is the co-moving time derivative.

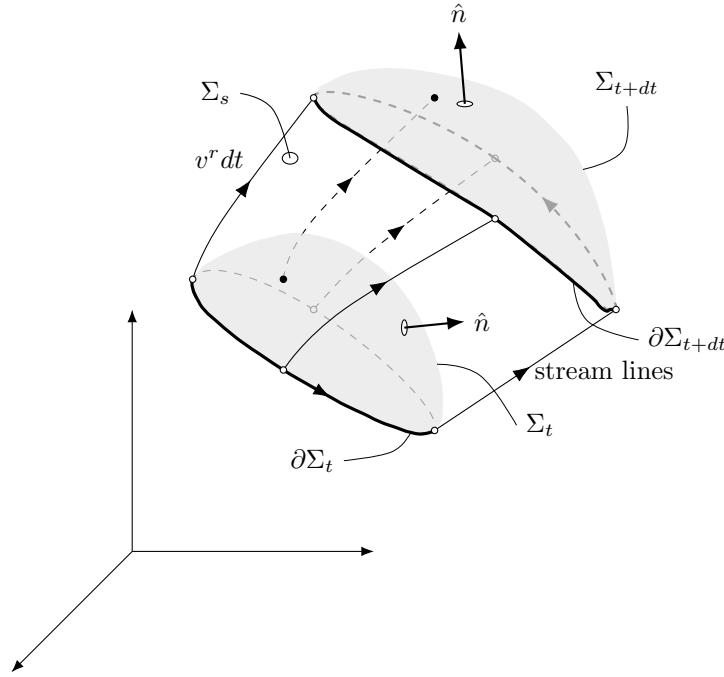


Figure 5.5: Evolution of a closed co-moving curve

Let's see what happens when a closed curve moves during a time dt . All the particles along that curve $\partial\Sigma_t$ will move along stream lines and will form a new closed curve $\partial\Sigma_{t+dt}$. Also all particles lying on a surface Σ_t enclosed by the closed curve will end on the surface Σ_{t+dt} . So we can use the Kelvin-Stokes theorem and form

$$\oint_{\partial\Sigma_{t+dt}} v_r dx^r - \oint_{\partial\Sigma_t} v_r dx^r = \iint_{\Sigma_{t+dt}} \epsilon_{rjk} v_{k,j} n^r dS - \iint_{\Sigma_t} \epsilon_{rjk} v_{k,j} (n^r) dS \quad (1)$$

Consider now the surface formed by the envelope of the stream lines starting from the curve $\partial\Sigma_t$.

What we try to achieve is to go from a curve integral to a volume integral using first the Kelvin-Stokes theorem followed by the divergence theorem and adding a term which we have to prove it is

equal to zero

$$\oint_{\partial\Sigma_{t+dt}} v_r dx^r - \oint_{\partial\Sigma_t} v_r dx^r = \iint_{\Sigma_{t+dt}} \epsilon_{rjk} v_{k,j} n^r dS - \iint_{\Sigma_t} \epsilon_{rjk} v_{k,j} (-n^r) dS + \underbrace{\iint_{\Sigma_s} \epsilon_{rjk} v_{k,j} n^r dS}_{=0?} \quad (2)$$

$$= \iint_{\Sigma_{t+dt}} \epsilon_{rjk} v_{k,j} n^r dS + \iint_{\Sigma_t} \epsilon_{rjk} v_{k,j} n^r dS + \underbrace{\iint_{\Sigma_s} \epsilon_{rjk} v_{k,j} n^r dS}_{=0?} \quad (3)$$

$$= \iiint_V \epsilon_{rjk} v_{k,jr} dV \quad (4)$$

$$= 0 \quad (5)$$

Note that in the second term of the right expression, we changed the sign of the normal vector \hat{n} as we want the normal vector on the surface point outward of the considered volume.

So we have to prove that indeed,

$$\iint_{\Sigma_s} \epsilon_{rjk} v_{k,j} n^r dS = 0 \quad (6)$$

Nothing that $n^r dS$ can be expressed as the cross product of $\bar{v} dt$ and $d\vec{l}$ (the last being the line segment along the curve $\partial_t \Sigma$), we have

$$n^r dS = \epsilon_{rpq} v^p dx^q dt \quad (7)$$

And get

$$\iint_{\Sigma_s} \epsilon_{rjk} v_{k,j} n^r dS = \iint_{\Sigma_s} \epsilon_{rjk} v_{k,j} \epsilon_{rpq} v^p dx^q dt \quad (8)$$

$$= \iint_{\Sigma_s} (\delta_{jp} \delta_{kq} - \delta_{jq} \delta_{kp}) v_{k,j} v^p dx^q dt \quad (9)$$

$$= \iint_{\Sigma_s} (v_{q,p} v^p dx^q - v_{p,q} v^p dx^q) dt \quad (10)$$

$$(v_p dt = dx^p) \Rightarrow \iint_{\Sigma_s} (v_{q,p} dx^p dx^q - v_{p,q} dx^p dx^q) \quad (11)$$

$$= 0 \quad (12)$$

So (5) is proven and get $d \oint_{\partial\Sigma_t} v_r dx^r = 0$ during an infinitesimal time dt giving

$$\frac{d}{dt} \oint_{\partial\Sigma_t} v_r dx^r = 0$$



5.31 p235 - Exercise 4

Curves having at each point the direction of the vorticity vector ω^r are called "vortex lines". Prove that $\oint_C v_r dx^r$ has the same value for all closed curves C which lie on the surface of the tube of vortex lines, and go once around the tube in the same sense. (Use Stokes' theorem; cf. 7.502.).

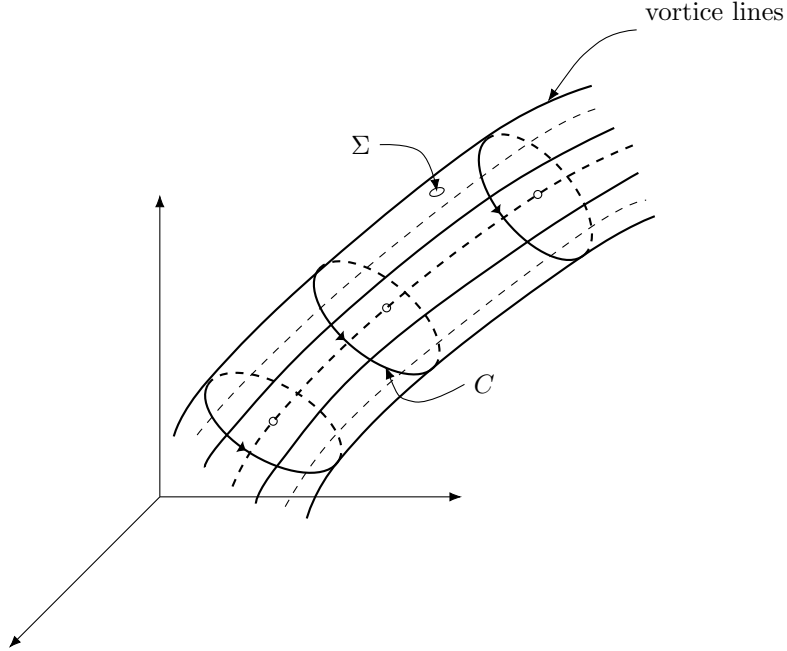


Figure 5.6: Vortex line tube

We have in rectangular Cartesian coordinates

$$(6.128) \quad \omega_{jk} = \frac{1}{2} (v_{k,j} - v_{j,k}) \quad (1)$$

$$(6.129) \quad \omega_r = \frac{1}{2} \epsilon_{rjk} \omega_{jk} \quad (2)$$

So we can use the Kelvin-Stokes theorem and form

$$\oint_{\partial \Sigma_{C'}} v_r dx^r - \oint_{\partial \Sigma_C} v_r dx^r = \iint_{\Sigma_{C'}} \epsilon_{rjk} v_{k,j} n^r dS - \iint_{\Sigma_C} \epsilon_{rjk} v_{k,j} n^r dS \quad (3)$$

Obviously, we have on the surface Σ_ω of the tube, $\hat{\omega} \cdot \hat{n}_\omega = 0$ and thus $\iint_{\Sigma_\omega} \omega_r n^r dS = 0$. Expanding the terms under the integral gives (by (6.129) and (6.128))

$$\iint_{\Sigma_\omega} \omega_r n^r dS = \frac{1}{4} \iint_{\Sigma_\omega} \epsilon_{rjk} (v_{k,j} - v_{j,k}) n^r dS \quad (4)$$

As $\iint_{\Sigma_\omega} \omega_r n^r dS = 0$ we can put

$$\iint_{\Sigma_\omega} \omega_r n^r dS = \frac{1}{2} \iint_{\Sigma_\omega} \epsilon_{rjk} v_{k,j} n^r dS - \frac{1}{2} \iint_{\Sigma_\omega} \epsilon_{rjk} v_{j,k} n^r dS \quad (5)$$

$$= \frac{1}{2} \iint_{\Sigma_\omega} \epsilon_{rjk} v_{k,j} n^r dS - \frac{1}{2} \iint_{\Sigma_\omega} \epsilon_{rkj} v_{k,j} n^r dS \quad (6)$$

$$= \frac{1}{2} \iint_{\Sigma_\omega} \epsilon_{rjk} v_{k,j} n^r dS + \frac{1}{2} \iint_{\Sigma_\omega} \epsilon_{rjk} v_{k,j} n^r dS \quad (7)$$

$$= \iint_{\Sigma_\omega} \epsilon_{rjk} v_{k,j} n^r dS \quad (= 0) \quad (8)$$

Adding (8) in (3) we get

$$\oint_{\partial\Sigma_{C'}} v_r dx^r - \oint_{\partial\Sigma_C} v_r dx^r = \iint_{\Sigma_{C'}} \epsilon_{rjk} v_{k,j} n^r dS + \iint_{\Sigma_C} \epsilon_{rjk} v_{k,j} n^r dS + \iint_{\Sigma_\omega} \epsilon_{rjk} v_{k,j} n^r dS \quad (9)$$

Note that in the second term of the right expression, we changed the sign of the normal vector \hat{n} as we want the normal vector on the surface point outward of the considered volume.

Using Green's theorem:

$$\oint_{\partial\Sigma_{C'}} v_r dx^r - \oint_{\partial\Sigma_C} v_r dx^r = \iint_{\Sigma_{C'}} \epsilon_{rjk} v_{k,j} n^r dS + \iint_{\Sigma_C} \epsilon_{rjk} v_{k,j} n^r dS + \iint_{\Sigma_\omega} \epsilon_{rjk} v_{k,j} n^r dS \quad (10)$$

$$= \iiint_V \epsilon_{rjk} v_{k,jr} dV \quad (11)$$

$$= 0 \quad (12)$$

where V is the volume enclosed by the surfaces Σ_C , $\Sigma_{C'}$ and Σ_ω .

And get $d \oint_{\partial\Sigma_t} v_r dx^r = 0$ along an infinitesimal displacement along the vortex line giving

$$\frac{d}{ds} \oint_{\partial\Sigma_t} v_r dx^r = 0$$

where s is a parameter upon which a vortex line can be expressed.

Hence $\oint_{\partial\Sigma_t} v_r dx^r$ is constant along a vortex line.

◆

5.32 p235 - Exercise 5

Prove that for the type of fluid described in Exercise 2, the vorticity tensor satisfies the differential equations

$$\frac{d}{dt}\omega_{rs} = \omega_{pr}v_{p,s} - \omega_{ps}v_{p,r}$$

the coordinates being rectangular Cartesians. Write these equations for curvilinear coordinates.

Deduce from these equations that, if $\omega_{rs} = 0$ initially at some point P in the fluid, these quantities will remain zero permanently for the particle which was initially at P .

Let's first write down some useful expressions:

We have in rectangular Cartesian coordinates

$$(6.128) \quad \omega_{jk} = \frac{1}{2}(v_{k,j} - v_{j,k}) \quad (1)$$

$$(6.129) \quad \omega_r = \frac{1}{2}\epsilon_{rjk}\omega_{jk} \quad (2)$$

$$\Rightarrow \quad \omega_r = \frac{1}{2}\epsilon_{rjk}(v_{k,j} - v_{j,k}) \quad (3)$$

$$= \frac{1}{2}\epsilon_{rjk}v_{k,j} - \frac{1}{2}\epsilon_{rjk}v_{j,k} \quad (4)$$

$$= \frac{1}{2}\epsilon_{rjk}v_{k,j} + \frac{1}{2}\epsilon_{rjk}v_{k,j} \quad (5)$$

$$= \frac{1}{2}\epsilon_{rjk}v_{k,j} \quad (6)$$

$$\Rightarrow \quad \omega_{r,r} = \frac{1}{2}\epsilon_{rjk}v_{k,jr} \quad (7)$$

$$= 0 \quad (8)$$

So we have, as the flow is steady

$$\frac{d}{dt}\omega_{rs} = \omega_{rs,p}v_p \quad (9)$$

$$(1): \quad = \frac{1}{2}(v_{s,rp} - v_{r,sp})v_p \quad (10)$$

We have also

$$(6.146) \quad \partial_t v_r + v_s v_{r,s} = X_r - \rho^{-1}p_{,r} \quad (11)$$

In the fluid considered here ($\partial_t v_r = 0$; $\rho = \rho(p) \Rightarrow \rho^{-1}p_{,r} := P_{,r}$; $X_r = -U_{,r}$) and get

$$v_s v_{r,s} + U_{,r} + P_{,r} = 0 \quad (12)$$

We are now able to deduce the asked expression.

Consider the following expression $\epsilon_{nmr}\epsilon_{nst}v_mv_tv_{t,s}$ This can be expressed as

$$\epsilon_{nrm}\epsilon_{nst}v_mv_tv_{t,s} = (\delta_{rs}\delta_{mt} - \delta_{rt}\delta_{ms})v_mv_tv_{t,s} \quad (13)$$

$$= v_mv_{m,r} - v_mv_{r,m} \quad (14)$$

giving

$$v_sv_{r,s} = v_sv_{s,r} - \epsilon_{nrm}\epsilon_{nst}v_mv_tv_{t,s} \quad (15)$$

So (12) can be expressed as

$$v_sv_{s,r} - \epsilon_{nrm}\epsilon_{nst}v_mv_tv_{t,s} + U_{,r} + P_{,r} = 0 \quad (16)$$

$$(6) \Rightarrow v_sv_{s,r} - 2\epsilon_{nrm}\omega_nv_m + U_{,r} + P_{,r} = 0 \quad (17)$$

$$v_sv_{s,r} + 2\epsilon_{rnm}\omega_nv_m + U_{,r} + P_{,r} = 0 \quad (18)$$

Let's take the curl of (18):

$$\epsilon_{pkr}(v_sv_{s,r})_{,k} + 2\epsilon_{pkr}\epsilon_{rnm}(\omega_nv_m)_{,k} + \epsilon_{pkr}U_{,rk} + \epsilon_{pkr}P_{,rk} = 0 \quad (19)$$

The terms with U and P are of the kind $\nabla \times \nabla(G)$ with G a scalar function $G : \mathbb{R}^3 \rightarrow \mathbb{R}$. These terms are equal to zero.

So, (19) becomes

$$\underbrace{\epsilon_{pkr}v_{s,k}v_{s,r}}_{=0} + \underbrace{\epsilon_{pkr}v_sv_{s,kr}}_{=0} + 2\epsilon_{pkr}\epsilon_{rnm}(\omega_nv_m)_{,k} = 0 \quad (20)$$

Nothing that,

$$\epsilon_{pkr}\epsilon_{rnm}(\omega_nv_m)_{,k} = \epsilon_{rpk}\epsilon_{rnm}(\omega_nv_m)_{,k} \quad (21)$$

$$= \delta_{pn}\delta_{km}(\omega_nv_m)_{,k} - \delta_{pm}\delta_{kn}(\omega_nv_m)_{,k} \quad (22)$$

$$= (\omega_pv_k)_{,k} - (\omega_kv_p)_{,k} \quad (23)$$

$$= \omega_{p,k}v_k + \omega_pv_{k,k} - \omega_{k,k}v_p - \omega_kv_{p,k} \quad (24)$$

Note that the divergence of the vorticity is zero, see (8), so

$$\epsilon_{pkr}\epsilon_{rnm}(\omega_nv_m)_{,k} = \omega_{p,k}v_k + \omega_pv_{k,k} - \omega_kv_{p,k} \quad (25)$$

(25) in (20) gives

$$\omega_{p,k}v_k + \omega_pv_{k,k} - \omega_kv_{p,k} = 0 \quad (26)$$

We have (6): $\omega_p = \frac{1}{2}\epsilon_{pmn}v_{n,m}$, $\omega_k = \frac{1}{2}\epsilon_{kmn}v_{n,m}$ giving for (26):

$$\epsilon_{pmn}v_{n,mk}v_k + \epsilon_{pmn}v_{n,m}v_{k,k} - \epsilon_{kmn}v_{n,m}v_{p,k} = 0 \quad (27)$$

this can also be expressed as

$$\epsilon_{pnm}v_{m,nk}v_k + \epsilon_{pnm}v_{m,n}v_{k,k} - \epsilon_{knm}v_{m,n}v_{p,k} = 0 \quad (28)$$

adding (27) and (28) gives

$$\epsilon_{pnm}(v_{m,nk} - v_{n,mk})v_k + \epsilon_{pnm}(v_{m,n} - v_{n,m})v_{k,k} - \epsilon_{knm}(v_{m,n} - v_{n,m})v_{p,k} = 0 \quad (29)$$

$$(1),(10): \quad \epsilon_{pmn}\frac{d\omega_{mn}}{dt} + \epsilon_{pmn}\omega_{mn}v_{k,k} - \epsilon_{kmn}\omega_{mn}v_{p,k} = 0 \quad (30)$$

$$\times \epsilon_{prs} \Rightarrow (\delta_{rm}\delta_{sn} - \delta_{rn}\delta_{ms})\frac{d\omega_{mn}}{dt} + (\delta_{rm}\delta_{sn} - \delta_{rn}\delta_{ms})\omega_{mn}v_{k,k} - \epsilon_{kmn}\omega_{mn}\epsilon_{prs}v_{p,k} = 0 \quad (31)$$

$$\Rightarrow \frac{d\omega_{rs}}{dt} - \frac{d\omega_{sr}}{dt} + (\omega_{rs} - \omega_{sr})v_{k,k} - \epsilon_{kmn}\omega_{mn}\epsilon_{prs}v_{p,k} = 0 \quad (32)$$

and as ω_{rs} is skew-symmetric

$$\frac{d\omega_{rs}}{dt} + \omega_{rs}v_{k,k} - \frac{1}{2}\epsilon_{kmn}\omega_{mn}\epsilon_{prs}v_{p,k} = 0 \quad (33)$$

Let's look at the term $\epsilon_{kmn}\omega_{mn}\epsilon_{prs}v_{p,k}$

Suppose $k = p$; then in order to have the term in $\epsilon_{(p)mn}\epsilon_{(p)rs}$ not equal to zero we need

$$(m = r \wedge n = s) \vee (m = s \wedge n = r) \quad \text{with } r \neq s$$

and get

$$\frac{1}{2} \sum_{(p)} \epsilon_{(p)mn}\omega_{mn}\epsilon_{(p)rs}v_{(p),(p)} = \frac{1}{2} \sum_{(p)} \epsilon_{(p)rs}\omega_{mn}\epsilon_{(p)rs}v_{(p),(p)} \quad (34)$$

$$= \frac{1}{2} \sum_{(p)} \left(\underbrace{\delta_{(p)(p)}}_{=1} \underbrace{\delta_{ss}}_{=2} - \underbrace{\delta_{(p)s}}_{=0} \delta_{(p)s} \right) \omega_{mn}v_{(p),(p)} \quad (35)$$

$$= \sum_{(p)} \omega_{rs}v_{(p),(p)} = \omega_{rs}v_{k,k} \quad (36)$$

($\delta_{ss} = 2$ as s can not take the value of (p) and so can only span two dimensions.)

Hence, the term $\omega_{rs}v_{k,k}$ in (33) vanishes.

Suppose now that $k \neq p$. We rewrite $\frac{1}{2}\epsilon_{kmn}\omega_{mn}\epsilon_{prs}v_{p,k}$ as

$$\frac{1}{2} \sum_{(p)} \sum_{(k)}^{p \neq k, k \neq p} \epsilon_{(k)mn} \omega_{mn} \epsilon_{(p)rs} v_{(p),(k)} \quad (37)$$

nothing that the explicit summation symbol only span two dimensions.

In (37) as $k \neq p$ we need that $m = p$ or $n = p$ and rewrite (37) as

$$\frac{1}{2} \sum_{(p)} \sum_{(k)}^{p \neq k, k \neq p} \epsilon_{(k)mn} \omega_{mn} \epsilon_{(p)rs} v_{(p),(k)} = \left\{ \begin{array}{l} \frac{1}{2} \sum_{(p)} \sum_{(k)} \epsilon_{(k)(p)n} \omega_{(p)n} \epsilon_{(p)rs} v_{(p),(k)} \\ + \frac{1}{2} \sum_{(p)} \sum_{(k)} \epsilon_{(k)m(p)} \omega_{m(p)} \epsilon_{(p)rs} v_{(p),(k)} \end{array} \right. \quad (38)$$

$$= \left\{ \begin{array}{l} \frac{1}{2} \sum_{(p)} \sum_{(k)} \epsilon_{(p)n(k)} \epsilon_{(p)rs} \omega_{(p)n} v_{(p),(k)} \\ + \frac{1}{2} \sum_{(p)} \sum_{(k)} \epsilon_{(p)m(k)} \epsilon_{(p)rs} \omega_{(p)m} v_{(p),(k)} \end{array} \right. \quad (39)$$

$$= \left\{ \begin{array}{l} \frac{1}{2} \sum_{(p)} \sum_{(k)} (\delta_{nr} \delta_{(k)s} - \delta_{ns} \delta_{(k)r}) \omega_{(p)n} v_{(p),(k)} \\ + \frac{1}{2} \sum_{(p)} \sum_{(k)} (\delta_{mr} \delta_{(k)s} - \delta_{(k)r} \delta_{ms}) \omega_{(p)m} v_{(p),(k)} \end{array} \right. \quad (40)$$

$$= \sum_{(p)} \omega_{(p)r} v_{(p),s} - \sum_{(p)} \omega_{(p)s} v_{(p),r} \quad (41)$$

(41) can now again be written as $\omega_{pr} v_{p,s} - \omega_{ps} v_{p,r}$ (this is possible because, although p only spans two dimensions, the skew-symmetry of ω_{ps} permits us to expand (p) to the three dimensions.)

Hence, (33) becomes

$$\frac{d\omega_{rs}}{dt} - (\omega_{pr} v_{p,s} - \omega_{ps} v_{p,r}) = 0$$

which is the expected expression.

◇

In curvilinear coordinates the expression becomes

$$\frac{\delta \omega_{rs}}{\delta t} = \omega_{pr} v_{p|s} - \omega_{ps} v_{p|r}$$

◇

Suppose that initially at a certain point $\omega_{rs} = 0$, then obviously $\frac{\delta \omega_{rs}}{\delta t} = \omega_{pr} v_{p|s} - \omega_{ps} v_{p|r} = 0$ and thus $\omega_{rs} = C$, a constant, which must be zero as the initial condition was that $\omega_{rs}(t=0) = 0$.

◇

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5.33 p236 - Exercise 6

By eliminating the three components of displacement u_r from the six equations **6.210**, obtain the following Cartesian equations of compatibility

$$e_{rs,mn} + e_{mn,rs} - e_{rm,sn} - e_{sn,rm} = 0$$

Show that there are only six independent equations here. Write the equations of compatibility in general tensor form.

We have **6.210**

$$e_{rs} = \frac{1}{2} (u_{r,s} + u_{s,r}) \quad (1)$$

and thus

$$\begin{aligned} (a) \quad e_{rs,mn} &= \frac{1}{2} (u_{r,smn} + u_{s,rnm}) \\ (b) \quad e_{mn,rs} &= \frac{1}{2} (u_{m,nrs} + u_{n,mrs}) \\ (c) \quad e_{rm,sn} &= \frac{1}{2} (u_{r,msn} + u_{m,rns}) \\ (d) \quad e_{sn,rm} &= \frac{1}{2} (u_{s,nrm} + u_{n,srm}) \end{aligned} \quad (2)$$

giving $e_{rs,mn} + e_{mn,rs} - e_{rm,sn} - e_{sn,rm} = (a) + (b) - (c) - (d) = 0$

◇

Consider the set (rs) . Considering the symmetries induced by the symmetry of e_{rs} , the number of possible combinations is one of type "repeated combination", i.e. $\binom{n+m-1}{m} = \frac{4!}{2!} = 6$. The same is true for the set (mn) , so the total of possible combinations is 36. But we notice that half of the combinations make the equation indiscernible of the other half; indeed when $(mn) = (rs)$, $e_{rs,mn} + e_{mn,rs} - e_{rm,sn} - e_{sn,rm} = e_{mn,rs} + e_{rs,mn} - e_{mr,ns} - e_{ns,mr} = 0$. This reduces the number of combinations to $\frac{36}{2} = 18$.

We notice that this is not the total possible number of independent equations yet, as some combinations make the identity trivial. Indeed, consider the case $m = s$. In this case the equation $e_{rs,(s)n} + e_{(s)n,rs} - e_{r(s),sn} - e_{sn,r(s)} = 0$ is trivial. The same is true for $n = r$, but also for $m = r$ and $n = s$. Indeed changing (rs) to (sr) (which is allowed as e_{rs} is symmetric) in $e_{rs,mn} + e_{mn,rs} - e_{rm,sn} - e_{sn,rm} = 0$ we get $e_{rs,mn} + e_{mn,rs} - e_{sm,rn} - e_{rn,sm} = 0$. This expression becomes also trivial when $n = s$ or $m = r$. So the number of independent equations reduces by the number of equations for which yield $m = r \vee m = s \vee n = r \vee n = s$. This number is $4 \times 3 = 12$ (4 independent events with 3 possible outcome, each).

So the total of independent equations is $18 - 12 = 6$.

◇

In general coordinate system we get,

$$e_{rs|mn} + e_{mn|rs} - e_{rm|sn} - e_{sn|rm} = 0$$

◆

5.34 p236 - Exercise 7

For a rectangular Cartesian coordinates z_r , a state of simple tension is represented as $E_{11} = C$ (a constant), all the other components of stress being zero. Find all six covariant components of stress for spherical polar coordinates.

We have **6.223** : $T_r = E_{rs}n_s$ so in rectangular Cartesian coordinates we have

$$T_1 = Cn_1 \quad T_2 = 0 \quad T_3 = 0 \quad (1)$$

In general we have when going from the rectangular Cartesian coordinates to a curvilinear coordinate system

$$T'_r = T_1 x'^1_{,r} \quad (2)$$

$$T'_r = E'_{rs} n'_s \quad (3)$$

$$n'^s = n^i x'^s_{,i} \quad (4)$$

$$n^1 = n'^s x'^1_{,s} \quad (5)$$

Putting this all together we can state

$$E'_{rs} n'^s = C n_1 x'^1_{,r} \quad (6)$$

$$E'_{rs} n'^s = C n'^s x'^1_{,s} x'^1_{,r} \quad (7)$$

From which we deduce

$$E'_{uv} = C x'^1_{,v} x'^1_{,u} \quad (8)$$

For spherical polar coordinates we have

$$\begin{cases} x^1 = r \sin \theta \cos \phi \\ x^1_{,r} = \sin \theta \cos \phi \\ x^1_{,\theta} = r \cos \theta \cos \phi \\ x^1_{,\phi} = -r \sin \theta \sin \phi \end{cases} \quad (9)$$

giving for (8)

$$\begin{cases} E_{rr} = C \sin^2 \theta \cos^2 \phi \\ E_{\theta\theta} = C r^2 \cos^2 \theta \cos^2 \phi \\ E_{\phi\phi} = C r^2 \sin^2 \theta \sin^2 \phi \\ E_{r\phi} = C r \sin \theta \cos \theta \cos^2 \phi \\ E_{r\theta} = C \sin^2 \theta \cos \phi \sin \phi \\ E_{\theta\phi} = -C r^2 \cos \theta \sin \theta \cos \phi \sin \phi \end{cases} \quad (10)$$



5.35 p236 - Exercise 8 †

By substitution from **6.247** in the Cartesian equations of compatibility in Exercise 6, deduce that in a homogeneous isotropic body in equilibrium under body forces X_r , the invariant $\Theta = E_{nn}$ satisfies the following partial differential equation:

$$(1 - \sigma) \Theta_{,rr} = (1 + \sigma) \rho X_{r,r}$$

Let's recap what we know

$$(a) \quad e_{rs,mn} + e_{mn,rs} - e_{rm,sn} - e_{sn,rm} = 0 \quad (\text{Exercise 6})$$

$$(b) \quad e_{rs} = \frac{1}{E} [(1 + \sigma) E_{rs} - \sigma \delta_{rs} E_{nn}] \quad (6.247)$$

$$(c) \quad E = \frac{\mu(3\lambda+2\mu)}{\lambda+\mu}, \quad \sigma = \frac{\lambda}{2(\lambda+\mu)} \quad (6.248)$$

$$(d) \quad \lambda = \frac{\sigma E}{(1+\sigma)(1-2\sigma)}, \quad \mu = \frac{E}{2(1+\sigma)} \quad (6.249) \quad (1)$$

$$(e) \quad \rho f_r = \rho X_r + (\lambda + \mu) \theta_{,r} + \mu \Delta u_r \quad (6.250)$$

$$(f) \quad \theta = e_{nn} \quad (6.246)$$

$$(g) \quad e_{rs} = \frac{1}{2} (u_{r,s} + u_{s,r}) \quad (6.210)$$

As we are in steady state we have $f_r = \frac{\partial^2 u_r}{\partial t^2} = 0$ and (e) becomes

$$\rho X_r + (\lambda + \mu) \theta_{,r} + \mu \Delta u_r = 0 \quad (2)$$

$$\Rightarrow \rho X_{r,r} + (\lambda + \mu) \theta_{,rr} + \mu (\Delta u_r)_{,r} = 0 \quad (3)$$

Put $m = n$ and $s = r$ in (a):

$$\underbrace{e_{rr,nn}}_{=\theta_{,nn}} + \underbrace{e_{nn,rr}}_{=\theta_{,nn}} - e_{rn,rn} - e_{rn,rn} = 0 \quad (4)$$

$$\text{or } \theta_{,nn} = e_{nr,nr} \quad (5)$$

Putting (b) in (5) we get

$$\theta_{,rr} = \frac{1}{E} [(1 + \sigma) E_{nr,nr} - \sigma \delta_{nr} E_{kk,nr}] \quad (6)$$

$$= \frac{1}{E} [(1 + \sigma) E_{nr,nr} - \sigma E_{kk,rr}] \quad (7)$$

$$= \frac{1}{E} (1 + \sigma) E_{nr,nr} - \frac{\sigma}{E} E_{kk,rr} \quad (8)$$

Put $\Theta = E_{kk}$, then

$$\theta_{,rr} = \frac{1}{E} (1 + \sigma) E_{nr,nr} - \frac{\sigma}{E} \Theta_{,rr} \quad (9)$$

Consider now $\Delta u_r = u_{r,kk}$, using $e_{rs} = \frac{1}{2} (u_{r,s} + u_{s,r})$ we have

$$e_{rs,rs} = \frac{1}{2} (u_{r,src} + u_{s,rrs}) \quad (10)$$

$$= u_{r,ssr} \quad (11)$$

but $u_{r,ss} = \Delta u_r$, then

$$(\Delta u_r)_{,r} = e_{rs,rs} \quad (12)$$

So, by (5),

$$(\Delta u_r)_{,r} = \theta_{,rr} \quad (13)$$

Let's recap what we already know. We have (3) and (13)

$$\begin{cases} (3) & \rho X_{r,r} + (\lambda + \mu) \theta_{,rr} + \mu \Delta (u_r)_{,r} = 0 \\ (13) & (\Delta u_r)_{,r} = \theta_{,rr} \end{cases} \quad (14)$$

and also

$$(1 + \sigma) E_{nr,nr} = (1 - \sigma) \Theta_{,rr} \quad (15)$$

indeed (a) gives

$$e_{rn,rn} = e_{rr,ss} \quad (16)$$

$$\Rightarrow \frac{1}{E} [(1 + \sigma) E_{rn,rn} - \sigma \delta_{rn} E_{kk,rn}] = \frac{1}{E} [(1 + \sigma) E_{rr,ss} - \sigma \delta_{rr} E_{kk,ss}] \quad (17)$$

$$\Leftrightarrow (1 + \sigma) E_{rn,rn} - \sigma \Theta_{,rr} = (1 + \sigma) \Theta_{,rr} - \sigma 3 \Theta_{,rr} \quad (18)$$

$$\Leftrightarrow (1 + \sigma) E_{rn,rn} = (1 - \sigma) \Theta_{,rr} \quad (19)$$

So, (9) becomes

$$\theta_{,rr} = \frac{1}{E} (1 + \sigma) E_{rn,rn} - \frac{\sigma}{E} \Theta_{,rr} \quad (20)$$

$$= \frac{1 - 2\sigma}{E} \Theta_{,rr} \quad (21)$$

and (14) becomes

$$(\Delta u_r)_{,r} = \frac{1 - 2\sigma}{E} \Theta_{,rr} \quad (22)$$

Let's put $\xi = (\lambda + \mu) \theta_{,rr} + \mu (\Delta u_r)_{,r}$ with (22) and (23) we get

$$\xi = \left[(\lambda + \mu) \frac{1 - 2\sigma}{E} + \mu \frac{1 - 2\sigma}{E} \right] \Theta_{,rr} \quad (23)$$

$$= \frac{1 - 2\sigma}{E} (\lambda + 2\mu) \Theta_{,rr} \quad (24)$$

Using (d) in this expression gives

$$\xi = \frac{1 - 2\sigma}{E} E \left(\frac{\sigma}{(1 + \sigma)(1 - 2\sigma)} + \frac{1}{(1 + \sigma)} \right) \Theta_{,rr} \quad (25)$$

$$= (1 - 2\sigma) \frac{\sigma + (1 - 2\sigma)}{(1 + \sigma)(1 - 2\sigma)} \Theta_{,rr} \quad (26)$$

$$= \frac{1 - \sigma}{1 + \sigma} \Theta_{,rr} \quad (27)$$

giving for (3)

$$(1 + \sigma) \rho X_{r,r} \quad \underbrace{\quad}_{\text{? should be -}} \quad (1 - \sigma) \Theta_{,rr} = 0$$



5.36 p236 - Exercise 9

In a state of plane stress we have $E_{\alpha 3} = 0, E_{33} = 0$, the coordinates being Cartesian, and Greek suffixes taking the values 1, 2. prove that the equations of equilibrium under no body forces are satisfied if we put

$$E_{\alpha\beta} = \epsilon_{\alpha\rho}\epsilon_{\beta\sigma}\psi_{,\rho\sigma}$$

where ψ is an arbitrary function. Show that this gives

$$E_{11} = \psi_{,22}, \quad E_{12} = -\psi_{,12}, \quad E_{22} = \psi_{,11},$$

Given that we are in equilibrium and no body forces acting we have from $\rho f_r = \rho X_r + E_{rs,s}$ we have

$$E_{rs,s} = 0 \tag{1}$$

Explicitly

$$E_{rs,s} = E_{r1,1} + E_{r2,2} + \underbrace{E_{r3,3}}_{=0} \tag{2}$$

and for $r = 3$

$$E_{3s,s} = \underbrace{E_{31,1}}_{=0} + \underbrace{E_{32,2}}_{=0} + \underbrace{E_{33,3}}_{=0} \tag{3}$$

So (1) can be expressed as

$$E_{\alpha\beta,\beta} = 0 \tag{4}$$

Let's test the expression $E_{\alpha\beta} = \epsilon_{\alpha\rho}\epsilon_{\beta\sigma}\psi_{,\rho\sigma}$

$$E_{\alpha\beta,\beta} = \epsilon_{\alpha\rho}\epsilon_{\beta\sigma}\psi_{,\rho\sigma\beta} \tag{5}$$

$$= 0 \tag{6}$$

The last identity is due to the fact that for a fixed α , or ρ will take the value of α (making $\epsilon_{\alpha\rho} = 0$, or for $\rho \neq \alpha$, the only non-zero terms imply that $\beta \neq \sigma$ where the expansion is of the form $\epsilon_{\alpha\rho}\epsilon_{\alpha\rho}\psi_{,\rho\sigma\beta} + \epsilon_{\alpha\rho}\epsilon_{\rho\alpha}\psi_{,\rho\sigma\beta}$ (no summation over dummy indexes) and as the order of partial differentiation is of no importance and $\epsilon_{\rho\alpha}$ and $\epsilon_{\alpha\rho}$ are of opposite sign, the two terms will cancel each other.

So indeed, $E_{\alpha\beta} = \epsilon_{\alpha\rho}\epsilon_{\beta\sigma}\psi_{,\rho\sigma}$ satisfies the differential equation $E_{rs,s} = 0$.

◇

Let's calculate explicitly the $E_{\alpha\beta}$.

$\epsilon_{\alpha\rho} \neq 0$ implies $\alpha \neq \rho$ and $\epsilon_{\beta\sigma} \neq 0$ implies $\beta \neq \sigma$, hence

$$\begin{aligned}
 E_{11} &= \epsilon_{12}\epsilon_{12}\psi_{,22} \\
 &= (1)(1)\psi_{,22} \\
 &= \psi_{,22} \\
 \\
 E_{22} &= \epsilon_{21}\epsilon_{21}\psi_{,11} \\
 &= (-1)(-1)\psi_{,11} \\
 &= \psi_{,11} \\
 \\
 E_{12} &= \epsilon_{12}\epsilon_{21}\psi_{,21} \\
 &= (1)(-1)\psi_{,21} \\
 &= -\psi_{,21}
 \end{aligned} \tag{7}$$

◆

5.37 p236 - Exercise 10

An isotropic elastic body is in equilibrium under no body forces. show that, for rectangular Cartesian coordinates, the displacement satisfies the partial differential equations

$$(1 - 2\sigma) \Delta u_r + \theta_{,r} = 0$$

Deduce that θ is a harmonic function.

Show that the above equations are satisfied if we put

$$u_r = \psi_r - \frac{1}{4(1 - \sigma)} (z_s \psi_s + \phi)_{,r}$$

provided $\Delta\phi = 0$, $\Delta\psi_r = 0$. (Papcovich-Neuber)

As we are in equilibrium (no acceleration) and no body forces, equation

$$6.250 \quad \rho f_r = \rho X_r + (\lambda + \mu) \theta_{,r} + \mu \Delta u_r$$

becomes

$$(\lambda + \mu) \theta_{,r} + \mu \Delta u_r = 0 \tag{1}$$

with

$$\lambda = \frac{\sigma E}{(1 + \sigma)(1 - 2\sigma)}, \quad \mu = \frac{E}{2(1 + \sigma)} \tag{2}$$

so (1) becomes

$$\frac{E}{(1 + \sigma)} \left(\frac{\sigma}{1 - 2\sigma} + \frac{1}{2} \right) \theta_{,r} + \frac{E}{2(1 + \sigma)} \Delta u_r = 0 \tag{3}$$

$$\Leftrightarrow \left(\frac{2\sigma + 1 - 2\sigma}{2(1 - 2\sigma)} \right) \theta_{,r} + \frac{1}{2} \Delta u_r = 0 \tag{4}$$

$$\Leftrightarrow \theta_{,r} + (1 - 2\sigma) \Delta u_r = 0 \tag{5}$$

◇

We show now that θ is an harmonic function .

$$(5)_{,r} \Rightarrow \theta_{,rr} + (1 - 2\sigma) (\Delta u_r)_{,r} = 0 \tag{6}$$

$$\Rightarrow \Delta \theta + (1 - 2\sigma) (\Delta u_r)_{,r} = 0 \tag{7}$$

We have

$$\Delta u_r = u_{r,ss} \tag{8}$$

$$\Rightarrow (\Delta u_r)_{,r} = u_{r,rss} \tag{9}$$

and from exercise 8 (11), (12), (13) we know

$$(\Delta u_r)_{,r} = \theta_{rr} = \Delta \theta \quad (10)$$

and (7) becomes

$$\Delta \theta + (1 - 2\sigma) \Delta \theta = 0 \quad (11)$$

$$\Rightarrow \Delta \theta = 0 \quad (12)$$

θ is an harmonic function.

◇

$$u_r = \psi_r - \frac{1}{4(1-\sigma)} (z_s \psi_s + \phi)_{,r} \quad (13)$$

$$\Rightarrow \Delta u_r = \underbrace{\Delta \psi_r}_{=0} - \frac{1}{4(1-\sigma)} \Delta (z_s \psi_s + \phi)_{,r} \quad (14)$$

$$= -\frac{1}{4(1-\sigma)} (z_s \psi_s + \phi)_{,rkk} \quad (15)$$

$$= -\frac{1}{4(1-\sigma)} \left[(z_{s,r} \psi_s + z_s \psi_{s,r})_{,kk} + \underbrace{\phi_{,rkk}}_{(\Delta \phi)_{,r}=0} \right] \quad (16)$$

$$= -\frac{1}{4(1-\sigma)} (\delta_{sr} \psi_s + z_s \psi_{s,r})_{,kk} \quad (17)$$

$$= -\frac{1}{4(1-\sigma)} (\psi_r + z_s \psi_{s,r})_{,kk} \quad (18)$$

$$= -\frac{1}{4(1-\sigma)} \left(\underbrace{\psi_{r,kk}}_{=0} + \left(\underbrace{z_{s,k}}_{=\delta_{sk}} \psi_{s,r} + z_s \psi_{s,rk} \right)_{,k} \right) \quad (19)$$

$$= -\frac{1}{4(1-\sigma)} \left(\psi_{k,rk} + z_{s,k} \psi_{s,rk} + z_s \underbrace{\psi_{s,rkk}}_{=0} \right) \quad (20)$$

$$= -\frac{1}{4(1-\sigma)} (\psi_{k,rk} + \psi_{k,rk}) \quad (21)$$

$$\Rightarrow \Delta u_r = -\frac{1}{2(1-\sigma)} \psi_{k,kr} \quad (22)$$

Let's look at $\theta = e_{nn}$. As $e_{rs} = \frac{1}{2} (u_{r,s} + u_{s,r})$

$$\theta = u_{k,k} \quad (23)$$

$$= \left(\psi_k - \frac{1}{4(1-\sigma)} (z_s \psi_s + \phi),_k \right),_k \quad (24)$$

$$= \psi_{k,k} - \frac{1}{4(1-\sigma)} \left((z_s \psi_s + \phi),_k \right),_k \quad (25)$$

$$= \psi_{k,k} - \frac{1}{4(1-\sigma)} \left((z_{s,k} \psi_s + z_s \psi_{s,k})_k + \underbrace{\phi_{,kk}}_{=0} \right) \quad (26)$$

$$= \psi_{k,k} - \frac{1}{4(1-\sigma)} (\psi_{k,k} + z_{s,k} \psi_{s,k} + z_s \psi_{s,kk}) \quad (27)$$

$$= \psi_{k,k} - \frac{1}{4(1-\sigma)} \left(\psi_{k,k} + \psi_{k,k} + z_s \underbrace{\psi_{s,kk}}_{=0} \right) \quad (28)$$

$$= \psi_{k,k} - \frac{1}{2(1-\sigma)} \psi_{k,k} \quad (29)$$

$$\Rightarrow \theta = \frac{1-2\sigma}{2(1-\sigma)} \psi_{k,k} \quad (30)$$

$$\Rightarrow \theta_{,r} = \frac{1-2\sigma}{2(1-\sigma)} \psi_{k,kr} \quad (31)$$

Be $\Gamma = (1-2\sigma) \Delta u_r + \theta_{,r}$ and let's plug into it (22) and (31)

$$\Gamma = (1-2\sigma) \Delta u_r + \theta_{,r} \quad (32)$$

$$= -(1-2\sigma) \frac{1}{2(1-\sigma)} \psi_{k,kr} + \frac{1-2\sigma}{2(1-\sigma)} \psi_{k,kr} \quad (33)$$

$$= 0 \quad (34)$$

and indeed

$$u_r = \psi_r - \frac{1}{4(1-\sigma)} (z_s \psi_s + \phi),_r$$

is a solution of

$$(1-2\sigma) \Delta u_r + \theta_{,r} = 0$$



5.38 p237 - Exercise 11

If, for rectangular Cartesian coordinates z_r , χ_{rs} is any symmetric tensor, show that the tensor E_{mn} defined by

$$E_{mn} = \epsilon_{mpr} \epsilon_{nqs} \chi_{rs,pq}$$

is symmetric, and satisfies the equations $E_{mn,n} = 0$.

Show that if we choose $\chi_{rs} = z_r z_s$, then $E_{mn} = -2\delta_{mn}$.

$$E_{nm} = \epsilon_{npr} \epsilon_{mqs} \chi_{rs,pq} \quad (1)$$

$$= \epsilon_{npr} \epsilon_{mqs} \chi_{sr,qp} \quad (2)$$

$$= \epsilon_{nqs} \epsilon_{mpr} \chi_{rs,pq} \quad (3)$$

$$= E_{mn} \quad (4)$$

◇

Consider

$$E_{mn,n} = \epsilon_{mpr} \epsilon_{nqs} \chi_{rs,pqn}$$

As ϵ_{nqs} is antisymmetric in (n, q) and $\chi_{rs,pqn}$ is symmetric in these indices, $E_{mn,n}$ reduces to a sum of terms of the type $\epsilon_{mpr} \epsilon_{(nq)s} \chi_{rs,p(qn)} - \epsilon_{mpr} \epsilon_{(nq)s} \chi_{rs,p(nq)}$.

So, $E_{mn,n} = 0$

◇

Be $\chi_{rs} = z_r z_s$, then

$$E_{mn} = \epsilon_{mpr} \epsilon_{nqs} (z_r z_s)_{,pq} \quad (5)$$

$$= \epsilon_{mpr} \epsilon_{nqs} (\delta_{pr} z_s + \delta_{sp} z_r)_{,q} \quad (6)$$

$$= \epsilon_{mpr} \epsilon_{nqs} (\delta_{pr} \delta_{sq} + \delta_{sp} \delta_{rq}) \quad (7)$$

$$= \underbrace{\epsilon_{mpp} \epsilon_{nqq}}_{=0} + \epsilon_{mpq} \epsilon_{nqp} \quad (8)$$

$$= \epsilon_{pmq} \epsilon_{pqn} \quad (9)$$

$$= \delta_{mq} \delta_{qn} - \delta_{mn} \underbrace{\delta_{qq}}_{=3} \quad (10)$$

$$= \delta_{mn} - 3\delta_{mn} \quad (11)$$

$$= -2\delta_{mn} \quad (12)$$

$$(13)$$

◆

5.39 p237 - Exercise 12

The determinantal equation $|\lambda\delta_{mn} - E_{mn}| = 0$ is important in elasticity because it gives the three principal stresses at a point. Show that if we introduce the three Cartesian invariants

$$A = E_{mn}, \quad B = E_{mm}E_{nn}, \quad C = E_{mn}E_{np}E_{pm}$$

the cubic equation may be written in the form

$$\lambda^3 - A\lambda^2 - \frac{1}{2}(A^2 - B)\lambda - \left(\frac{1}{6}A^3 - \frac{1}{2}AB + \frac{1}{3}C\right) = 0$$

[Hint: Note the Cartesian invariance of this expression, and use coordinates which make $E_{rs} = 0$ for $r \neq s$.]

Be a matrix M_{pq} . Its determinant can be expressed as $|M_{pq}| = \epsilon_{mnr}M_{1m}M_{2n}M_{3r}$ or - see (4.316) - $\epsilon_{stu}|M_{pq}| = \epsilon_{mnr}M_{sm}M_{tn}M_{ur}$ or $\epsilon_{stu}\epsilon_{stu}|M_{pq}| = 6|M_{pq}| = \epsilon_{stu}\epsilon_{mnr}M_{sm}M_{tn}M_{ur}$.

Put

$$M_{pq} = \lambda\delta_{mn} - E_{mn}$$

and get

$$6|M_{pq}| = \epsilon_{stu}\epsilon_{mnr}(\lambda\delta_{sm} - E_{sm})(\lambda\delta_{tn} - E_{tn})(\lambda\delta_{ur} - E_{ur}) \quad (1)$$

$$= \begin{cases} \epsilon_{stu}\epsilon_{mnr} \{ \\ \lambda^3\delta_{sm}\delta_{tn}\delta_{ur} \\ -\lambda^2\delta_{sm}\delta_{ur}E_{tn} - \lambda^2\delta_{tn}\delta_{ur}E_{sm} - \lambda^2\delta_{sm}\delta_{tn}E_{ur} \\ +\lambda\delta_{ur}E_{sm}E_{tn} + \lambda\delta_{sm}E_{tn}E_{ur} + \lambda\delta_{tn}E_{sm}E_{ur} \\ -E_{sm}E_{tn}E_{ur} \\ \} \end{cases} \quad (2)$$

$$= \begin{cases} \lambda^3 \underbrace{\epsilon_{stu}\epsilon_{stu}}_{=6} \\ -\lambda^2 \underbrace{\epsilon_{stu}\epsilon_{snu}}_{=2\delta_{tn}} E_{tn} - \lambda^2 \underbrace{\epsilon_{stu}\epsilon_{mtu}}_{=2\delta_{sm}} E_{sm} - \lambda^2 \underbrace{\epsilon_{stu}\epsilon_{str}}_{=2\delta_{ur}} E_{ur} \\ +\lambda \underbrace{\epsilon_{stu}\epsilon_{mnu}}_{=\delta_{sm}\delta_{tn}-\delta_{sn}\delta_{tm}} E_{sm}E_{tn} + \lambda \underbrace{\epsilon_{stu}\epsilon_{snr}}_{=\delta_{tn}\delta_{ur}-\delta_{tr}\delta_{un}} E_{tn}E_{ur} + \lambda \underbrace{\epsilon_{stu}\epsilon_{mtr}}_{=\delta_{sm}\delta_{ur}-\delta_{sm}\delta_{ur}} E_{sm}E_{ur} \\ -\epsilon_{stu}\epsilon_{mnr}E_{sm}E_{tn}E_{ur} \end{cases} \quad (3)$$

working out gives

$$6|M_{pq}| = 6\lambda^3 - 6A\lambda^2 + (3A^2 - 3B)\lambda - \epsilon_{stu}\epsilon_{mnr}E_{sm}E_{tn}E_{ur} \quad (4)$$

but the term $\epsilon_{stu}\epsilon_{mnr}E_{sm}E_{tn}E_{ur} = 6|E_{pq}|$ giving

$$|M_{pq}| = \lambda^3 - A\lambda^2 + \frac{1}{2}(A^2 - B)\lambda - |E_{pq}| \quad (5)$$

Let's consider now the invariants

$$A = E_{mn}, \quad B = E_{mm}E_{nn}, \quad C = E_{mn}E_{np}E_{pm}$$

As (E_{pq}) is symmetric with elements $\in \mathbb{R}$, we know that there is an orthogonal transformations so that (E_{pq}) becomes diagonal:

$$(E_{pq}) = \begin{pmatrix} E_1 & 0 & 0 \\ 0 & E_2 & 0 \\ 0 & 0 & E_3 \end{pmatrix} \quad (6)$$

The invariants A , B , C become

$$\begin{cases} A = E_1 + E_2 + E_3 \\ B = E_1^2 + E_2^2 + E_3^2 \\ C = E_1^3 + E_2^3 + E_3^3 \\ |E_{pq}| = E_1 E_2 E_3 \end{cases} \quad (7)$$

We will try to express $|E_{pq}|$ as an expression of A , B , C . Obviously as $|E_{pq}| = E_1 E_2 E_3$ we need at least A^3

$$A^3 = \begin{cases} E_1^3 + E_2^3 + E_3^3 \\ + 3E_1 E_2^2 + 3E_1 E_3^2 + 3E_2^2 E_1 + 3E_1^2 E_3 + 3E_2^2 E_3 + 3E_3^2 E_2 \\ + 6E_1 E_2 E_3 \end{cases} \quad (8)$$

$$= C + 6|E_{pq}| + 3(E_1 E_2^2 + E_1 E_3^2 + E_2^2 E_1 + E_1^2 E_3 + E_2^2 E_3 + E_3^2 E_2) \quad (9)$$

and AB

$$AB = (E_1 + E_2 + E_3)(E_1^2 + E_2^2 + E_3^2) \quad (10)$$

$$= E_1^3 + E_2^3 + E_3^3 + E_1 E_2^2 + E_1 E_3^2 + E_1^2 E_2 + E_1^2 E_3 + E_2^2 E_3 + E_3^2 E_2 \quad (11)$$

$$= C + E_1 E_2^2 + E_1 E_3^2 + E_1^2 E_2 + E_1^2 E_3 + E_2^2 E_3 + E_3^2 E_2 \quad (12)$$

hence

$$A^3 - 3AB = C + 6|E_{pq}| - 3C \quad (13)$$

$$= 6|E_{pq}| - 2C \quad (14)$$

$$\Rightarrow 6|E_{pq}| = A^3 - 3AB + 2C \quad (15)$$

and (5) becomes

$$|M_{pq}| = \lambda^3 - A\lambda^2 + \frac{1}{2}(A^2 - B)\lambda - \left(\frac{1}{6}A^3 - \frac{1}{2}AB + \frac{1}{3}C\right) \quad (16)$$

Putting $|M_{pq}| = 0$ gives the required equation.



5.40 p237 - Exercise 13

A plane electromagnetic wave in complex form is given,

$$E_\alpha = A_\alpha e^{iS}, \quad E_3 = 0, \quad H_\alpha = -\epsilon_{\alpha\beta} A_\beta e^{iS}, \quad H_3 = 0$$

$$S = \frac{2\pi}{\lambda} (z_3 - ct)$$

where A_α is a constant complex vector, and Greek suffixes take the values 1, 2. Verify that Maxwell's equations are satisfied, and that the wave is propagated in the positive z_3 -direction.

The wave meets a perfectly conducting wall $z_3 = 0$, and is reflected. Given the condition on such wall is that the tangential component of the electric vector for the total field vanishes, show that the reflected wave is given by

$$E'_\alpha = -A_\alpha e^{iS'}, \quad E'_3 = 0, \quad H'_\alpha = -\epsilon_{\alpha\beta} A_\beta e^{iS'}, \quad H'_3 = 0,$$

$$S' = -\frac{2\pi}{\lambda} (z_3 + ct)$$

Maxwell's equations read

$$\left\{ \begin{array}{ll} (6.301) & \frac{1}{c} \partial_t E_r = \epsilon_{rmn} H_{n,m} \quad \frac{1}{c} \partial_t H_r = -\epsilon_{rmn} E_{n,m} \\ (6.302) & E_{n,n} = 0 \quad H_{n,n} = 0 \end{array} \right. \quad (1)$$

For (6.302) this gives for the considered case

$$E_{n,n} = E_{\alpha,\alpha} + \underbrace{E_{3,3}}_{=0} \quad (2)$$

$$= A_\alpha (e^{iS})_{,\alpha} \quad (3)$$

$$= i A_\alpha e^{iS} \underbrace{S_{,\alpha}}_{=0} \quad (4)$$

$$= 0 \quad (5)$$

analogously

$$H_{n,n} = H_{\alpha,\alpha} + \underbrace{H_{3,3}}_{=0} \quad (6)$$

$$= -\epsilon_{\alpha\beta} A_\beta (e^{iS})_{,\alpha} \quad (7)$$

$$= -i \epsilon_{\alpha\beta} A_\beta \underbrace{S_{,\alpha}}_{=0} \quad (8)$$

$$= 0 \quad (9)$$

So for **6.302** the considered wave meets Maxwell's equations.

And for **6.301**

$$\frac{1}{c}\partial_t E_\alpha = \epsilon_{\alpha mn} H_{n,m} \quad (10)$$

$$\epsilon_{\alpha mn} H_{n,m} = \epsilon_{\alpha\beta\gamma} H_{\gamma,\beta} + \epsilon_{\alpha3\beta} H_{\beta,3} + \underbrace{\epsilon_{\alpha\beta3} H_{3,\gamma}}_{=0} \quad (11)$$

$$= -i\epsilon_{\alpha\beta\gamma}\epsilon_{\gamma\delta} A_\delta e^{iS} \underbrace{S_{,\beta}}_{=0} - i\epsilon_{\alpha3\beta}\epsilon_{\beta\gamma} A_\gamma e^{iS} \underbrace{S_{,3}}_{=\frac{2\pi}{\lambda}} \quad (12)$$

$$= -i\frac{2\pi}{\lambda}\epsilon_{\alpha3\beta}\epsilon_{\beta\gamma} A_\gamma e^{iS} \quad (13)$$

$$= i\frac{2\pi}{\lambda}\epsilon_{\alpha\beta3}\epsilon_{\beta\gamma} A_\gamma e^{iS} \quad (14)$$

Let's look at (14) and more specifically at the factor $\epsilon_{\alpha\beta3}$. As the third index is fixed we can replace $\epsilon_{\alpha\beta3}$ by $\epsilon_{\alpha\beta}$ and get

$$\epsilon_{\alpha mn} H_{n,m} = i\frac{2\pi}{\lambda}\epsilon_{\alpha\beta}\epsilon_{\beta\gamma} A_\gamma e^{iS} \quad (15)$$

$$= -i\frac{2\pi}{\lambda} A_\alpha e^{iS} \quad (16)$$

and

$$\frac{1}{c}\partial_t E_\alpha = \frac{1}{c} i A_\alpha e^{iS} \left(-c \frac{2\pi}{\lambda} \right) \quad (17)$$

$$= -i\frac{2\pi}{\lambda} A_\alpha e^{iS} \quad (18)$$

So for **6.301(a)** the considered wave meets Maxwell's equations.

For the second equation:

$$\frac{1}{c}\partial_t H_\alpha = -\epsilon_{\alpha mn} E_{n,m} \quad (19)$$

$$\epsilon_{\alpha mn} E_{n,m} = -\epsilon_{\alpha\beta\gamma} \underbrace{E_{\gamma,\beta}}_{=0} - \epsilon_{\alpha3\beta} E_{\beta,3} - \epsilon_{\alpha\beta3} \underbrace{E_{3,\gamma}}_{=0} \quad (20)$$

$$= -\epsilon_{\alpha3\beta} E_{\beta,3} \quad (21)$$

$$= -i\frac{2\pi}{\lambda}\epsilon_{\alpha3\beta} A_\beta e^{iS} \quad (22)$$

$$= i\frac{2\pi}{\lambda}\epsilon_{\alpha\beta} A_\beta e^{iS} \quad (23)$$

$$\frac{1}{c}\partial_t H_\alpha = i\frac{2\pi}{\lambda}\epsilon_{\alpha\beta} A_\beta e^{iS} \quad (24)$$

So for **6.301(b)** the considered wave meets Maxwell's equations and also for all the other equations in Maxwell's equations set.

◇

As in the equation of the plane the only varying parameter is $S = \frac{2\pi}{\lambda}(z_3 - ct)$ (depending on space and time), the components of E_r , H_r will remain constant only when $S = \text{constant}$ and as S is

only spatially dependent of z_3 the plane can only move in the z_3 -direction. Indeed, at a certain configuration point (z_1, z_2, z_3, t) the configuration is the same $\forall z_1, z_2$ for a given pair (z_3, t) . At a time t' the value of E_r, H_r will be the same if $z_3 - ct = z'_3 - ct'$, giving $z'_3 = z_3 + c(t' - t)$: a plane with certain configuration (z_1, z_2, z_3, t_0) will move along the z_3 axis with speed c

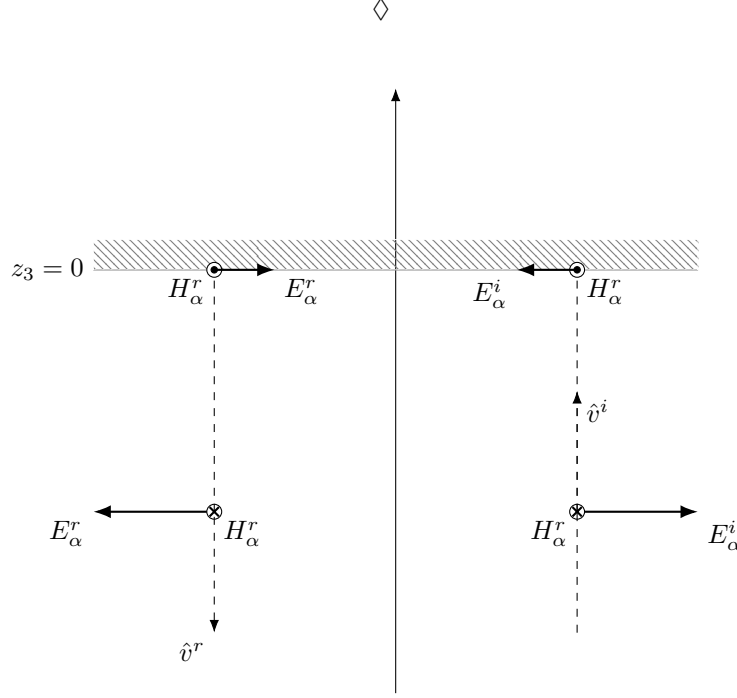


Figure 5.7: Reflection of a plane wave

At the wall we have $E_\alpha^t = E_\alpha^i + E_\alpha^r = 0$, with E_α^t the total field and E_α^i, E_α^r the incoming and reflected field. Without loss of generalization we can put at the wall $t = 0$ and $z_3 = 0$ so we get

$$E_\alpha^r = -A_\alpha$$

so the reflection gives an opposite sign to the electric field of the reflected plane wave.

We note also that the velocity of the wave is reversed, so in the definition of the incoming wave we replace c by $-c$ we get

$$E_\alpha^r = -A_\alpha e^{i \frac{2\pi}{\lambda} (z_3 + ct)} \quad (25)$$

It is easily checked, see above, that the wave moves along the z_3 axis in the negatives sense, which is what we want.

This expression could be a candidate to describe the reflected wave.

But we note that

$$E_\alpha^r = -A_\alpha e^{-i \frac{2\pi}{\lambda} (z_3 + ct)} \quad (26)$$

also represents an electric field moving in the negative sense of z_3 .

Let's further note that the triad $E_\alpha^r, H_\alpha^r, v^r$ (with v^r the velocity vector), is an oriented triad. As the velocity vector and electric field of the incoming field both are reversed, we conclude that the magnetic vector will maintain it's direction (see figure).

So, let's put tentatively for the magnetic complex vector

$$H_\alpha^r = -\epsilon_{\alpha\beta} A_\beta e^{i\frac{2\pi}{\lambda}(z_3+ct)} \quad (27)$$

or

$$H_\alpha^r = -\epsilon_{\alpha\beta} A_\beta e^{-i\frac{2\pi}{\lambda}(z_3+ct)} \quad (28)$$

We test now these tentative equations with the Maxwell's equations.

Electric field : (6.301a)

Case $S = \frac{2\pi}{\lambda}(z_3 + ct_0)$

$$\frac{1}{c}\partial_t E_\alpha = \epsilon_{\alpha mn} H_{n,m} \quad (29)$$

$$\epsilon_{\alpha mn} H_{n,m} = \epsilon_{\alpha\beta\gamma} H_{\gamma,\beta} + \epsilon_{\alpha 3\beta} H_{\beta,3} + \epsilon_{\alpha\beta 3} \underbrace{H_{3,\gamma}}_{=0} \quad (30)$$

$$= -i\epsilon_{\alpha\beta\gamma}\epsilon_{\gamma\delta} A_\delta e^{iS} \underbrace{S_{,\beta}}_{=0} - i\epsilon_{\alpha 3\beta}\epsilon_{\beta\gamma} A_\gamma e^{iS} \underbrace{S_{,3}}_{=\frac{2\pi}{\lambda}} \quad (31)$$

$$= -i\frac{2\pi}{\lambda} A_\alpha e^{iS} \quad (32)$$

$$\frac{1}{c}\partial_t E_\alpha = -\frac{1}{c}iA_\alpha e^{iS} \left(c\frac{2\pi}{\lambda}\right) \quad (33)$$

$$= -i\frac{2\pi}{\lambda} A_\alpha e^{iS} \quad (34)$$

Case $S = -\frac{2\pi}{\lambda}(z_3 + ct_0)$

$$\frac{1}{c}\partial_t E_\alpha = \epsilon_{\alpha mn} H_{n,m} \quad (35)$$

$$\epsilon_{\alpha mn} H_{n,m} = \epsilon_{\alpha\beta\gamma} H_{\gamma,\beta} + \epsilon_{\alpha 3\beta} H_{\beta,3} + \epsilon_{\alpha\beta 3} \underbrace{H_{3,\gamma}}_{=0} \quad (36)$$

$$= -i\epsilon_{\alpha\beta\gamma}\epsilon_{\gamma\delta} A_\delta e^{iS} \underbrace{S_{,\beta}}_{=0} - i\epsilon_{\alpha 3\beta}\epsilon_{\beta\gamma} A_\gamma e^{iS} \underbrace{S_{,3}}_{=-\frac{2\pi}{\lambda}} \quad (37)$$

$$= i\frac{2\pi}{\lambda} A_\alpha e^{iS} \quad (38)$$

$$\frac{1}{c}\partial_t E_\alpha = -\frac{1}{c}iA_\alpha e^{iS} \left(-c\frac{2\pi}{\lambda}\right) \quad (39)$$

$$= i\frac{2\pi}{\lambda} A_\alpha e^{iS} \quad (40)$$

So, both solutions satisfies the Maxwell equation **6.301a**.

Magnetic field : (6.301b)**Case** $S = \frac{2\pi}{\lambda} (z_3 + ct_0)$

$$\frac{1}{c} \partial_t H_\alpha = -\epsilon_{\alpha mn} E_{n,m} \quad (41)$$

$$\epsilon_{\alpha mn} E_{n,m} = -\epsilon_{\alpha\beta\gamma} \underbrace{E_{\gamma,\beta}}_{=0} - \epsilon_{\alpha 3\beta} E_{\beta,3} - \epsilon_{\alpha\beta 3} \underbrace{E_{3,\gamma}}_{=0} \quad (42)$$

$$= \epsilon_{\alpha\beta 3} E_{\beta,3} \quad (43)$$

$$= -i \frac{2\pi}{\lambda} \epsilon_{\alpha 3\beta} A_\beta e^{iS} \quad (44)$$

$$= i \frac{2\pi}{\lambda} \epsilon_{\alpha\beta} A_\beta e^{iS} \quad (45)$$

$$\frac{1}{c} \partial_t H_\alpha = i \frac{2\pi}{\lambda} \epsilon_{\alpha\beta} (-A_\beta) e^{iS} \quad (46)$$

$$= -i \frac{2\pi}{\lambda} \epsilon_{\alpha\beta} A_\beta e^{iS} \quad (47)$$

Case $S = -\frac{2\pi}{\lambda} (z_3 + ct_0)$

$$\frac{1}{c} \partial_t H_\alpha = -\epsilon_{\alpha mn} E_{n,m} \quad (48)$$

$$\epsilon_{\alpha mn} E_{n,m} = -\epsilon_{\alpha\beta\gamma} \underbrace{E_{\gamma,\beta}}_{=0} - \epsilon_{\alpha 3\beta} E_{\beta,3} - \epsilon_{\alpha\beta 3} \underbrace{E_{3,\gamma}}_{=0} \quad (49)$$

$$= \epsilon_{\alpha\beta 3} E_{\beta,3} \quad (50)$$

$$= i \frac{2\pi}{\lambda} \epsilon_{\alpha\beta} A_\beta e^{iS} \quad (51)$$

$$\frac{1}{c} \partial_t H_\alpha = -i \frac{2\pi}{\lambda} \epsilon_{\alpha\beta} (-A_\beta) e^{iS} \quad (52)$$

$$= i \frac{2\pi}{\lambda} \epsilon_{\alpha\beta} A_\beta e^{iS} \quad (53)$$

We conclude that $S = \frac{2\pi}{\lambda} (z_3 + ct_0)$ does not fit with the Maxwell's equations while $S = -\frac{2\pi}{\lambda} (z_3 + ct_0)$ does.

For the z_3 components of the electric and magnetic field, these must remain zero as all the energy the plane components of the incoming electromagnetic wave is transferred to the plane components of the reflected plane wave (the magnitude of these components are the same for the incoming and the reflected plane wave).



5.41 p238 - Exercise 14

Taking for the Hertz vector the fundamental solution of the wave equation **6.342**

$$\Pi_r = B_r \frac{e^{-ik(ct-R)}}{R}, \quad R^2 = z_m z_m$$

where B_r is a constant vector, show that, for R much less than $\lambda = \frac{2\pi}{k}$, we have approximately

$$E_r = -\frac{\partial}{\partial z^r} \left[B_m z_m \frac{e^{-ikct}}{R^3} \right],$$

$$H_r = -ik\epsilon_{rmn} B_m z_n \frac{e^{-ikct}}{R^3}.$$

Show also that for R much greater than $\lambda = \frac{2\pi}{k}$ (wave zone), we have approximately

$$E_r = k^2 (B_r R^2 - B_m z_m z_r) \frac{e^{-ik(ct-R)}}{R^3},$$

$$H_r = -k^2 \epsilon_{rmn} B_m z_n \frac{e^{-ik(ct-R)}}{R^2}.$$

(This is the electromagnetic field of the Hertzian dipole oscillation, which is the simplest model of a radio antenna).

We have **6.341**:

$$E_r = \Pi_{m,mr} - \frac{1}{c^2} \partial_t^2 \Pi_r \quad (1)$$

$$H_r = \frac{1}{c} \epsilon_{rpq} \partial_t \Pi_{q,p} \quad (2)$$

and **6.342**:

$$\frac{1}{c^2} \partial_t^2 \Pi_r - \Pi_{r,mm} = 0 \quad (3)$$

(3) in (1):

$$E_r = \Pi_{m,mr} - \Pi_{r,mm} \quad (4)$$

One is tempted to attack frontally the expression (4) but when you begin, one experiences that this approach requires a lot of lengthy algebraic manipulations. So instead we try first to derive the expression for the magnetic field and then derive the electric field from the Maxwell's equations.

Let's express Π_r as

$$\Pi_r = B_r G(t) F(z) \quad (5)$$

with

$$G(t) = e^{-ikt} \quad (6)$$

$$F(z) = \frac{e^{ikR}}{R} \quad (7)$$

From **6.348** we have

$$F' = \frac{\partial F}{\partial R} = \left(\frac{ik}{R} - \frac{1}{R^2} \right) e^{ikR} \quad (8)$$

and

$$R_{,r} = \frac{z_r}{R} \quad (9)$$

We have (2)

$$H_r = \frac{1}{c} \epsilon_{rpq} \partial_t \Pi_{q,p} \quad (10)$$

with

$$\Pi_{q,p} = B_q G F' R_{,p} \quad (11)$$

$$= B_q z_p G F \left(\frac{ik}{R} - \frac{1}{R^2} \right) \quad (12)$$

$$\Rightarrow \partial_t \Pi_{q,p} = B_q z_p F \left(\frac{ik}{R} - \frac{1}{R^2} \right) \partial_t G \quad (13)$$

$$= -ikc B_q z_p G F \left(\frac{ik}{R} - \frac{1}{R^2} \right) \quad (14)$$

$$\Rightarrow H_r = -ik \epsilon_{rpq} B_q z_p G F \left(\frac{ik}{R} - \frac{1}{R^2} \right) \quad (15)$$

For $kR \ll 2\pi$ we have

$$F = \frac{e^{ikR}}{R} = \frac{\cos kR + i \sin kR}{R} \approx \frac{1 + ikR}{R} = \left(\frac{1}{R} + ik \right) \quad (16)$$

So (15) becomes

$$H_r = -ik\epsilon_{rpq}B_qz_pG\left(\frac{1}{R} + ik\right)\left(\frac{ik}{R} - \frac{1}{R^2}\right) \quad (17)$$

$$= -ik\epsilon_{rpq}B_qz_pG\left(\frac{1}{R} + ik\right)\left(ik - \frac{1}{R}\right)\frac{1}{R} \quad (18)$$

$$= -ik\epsilon_{rpq}B_qz_pG\left(-k^2 - \frac{1}{R^2}\right)\frac{1}{R} \quad (19)$$

$$= i\epsilon_{rpq}B_qz_pG\left(k^3 + \frac{k}{R^2}\right)\frac{1}{R} \quad (20)$$

$$= i\epsilon_{rpq}B_qz_pG\left(k^3 + \frac{k^3}{k^2R^2}\right)\frac{1}{R} \quad (21)$$

$$= ik^3\epsilon_{rpq}B_qz_pG\left(1 + \frac{1}{k^2R^2}\right)\frac{1}{R} \quad (22)$$

and as $\frac{1}{k^2R^2} \gg 1$

$$H_r = ik^3\epsilon_{rpq}B_qz_pG\frac{1}{k^2R^2}\frac{1}{R} \quad (23)$$

$$= ik\epsilon_{rpq}B_qz_p\frac{1}{R^3}e^{-ikct} \quad (24)$$

$$= -ik\epsilon_{rmn}B_mz_n\frac{1}{R^3}e^{-ikct} \quad (25)$$

so indeed

$$\mathbf{H}_r \approx -i\mathbf{k}\epsilon_{rmn}\mathbf{B}_m\mathbf{z}_n\frac{1}{R^3}e^{-ikct}$$

For the electric field we have the Maxwell equation (for the case $kR \ll 2\pi$)

$$\frac{1}{c}\partial_t E_r = \epsilon_{rmn}H_{n,m} \quad (26)$$

$$= -ik\epsilon_{rmn}\epsilon_{npq}B_pG\left(z_q\frac{1}{R^3}\right)_{,m} \quad (27)$$

$$= -ik\epsilon_{rmn}\epsilon_{npq}B_pG(z_q)_{,m}\frac{1}{R^3} + ik\epsilon_{rmn}\epsilon_{npq}B_pGz_q\left(\frac{1}{R^3}\right)_{,m} \quad (28)$$

$$= -ik\underbrace{\epsilon_{rmn}\epsilon_{npm}}_{=2\delta_{rp}}B_pG\frac{1}{R^3} + 3ik\underbrace{\epsilon_{rmn}\epsilon_{npq}}_{=-\delta_{mp}\delta_{rq}+\delta_{nq}\delta_{rp}}B_pGz_q\frac{z_m}{R^5} \quad (29)$$

$$= ikG\left(\frac{B_r}{R^3} - 3\frac{B_mz_mz_r}{R^5}\right) \quad (30)$$

and note that

$$\left(\frac{B_r}{R^3} - 3\frac{B_mz_mz_r}{R^5}\right) = \left[\frac{B_mz_m}{R^3}\right]_{,r}$$

so integration over t of (30)

$$E_r = \left[ikc \frac{B_m z_m}{R^3} \underbrace{\int G dt}_{-\frac{e^{-ikct}}{ikc}} \right]_{,r} \quad (31)$$

$$= - \left[i B_m z_m \frac{e^{-ikct}}{R^3} \right]_{,r} \quad (32)$$

so indeed

$$\mathbf{E}_r \approx - \left[i \mathbf{B}_m \mathbf{z}_m \frac{\mathbf{e}^{-ikct}}{\mathbf{R}^3} \right]_{,r}$$

◇

Let's look at the case $kR \gg 2\pi$:

We have (15)

$$H_r = -ik\epsilon_{rpq} B_q z_p G F \left(\frac{ik}{R} - \frac{1}{R^2} \right) \quad (33)$$

$$= -ik^3 \epsilon_{rpq} B_q z_p G F \left(\frac{i}{kR} - \frac{1}{k^2 R^2} \right) \quad (34)$$

as $\frac{1}{kR} \gg \frac{1}{k^2 R^2}$ we discard the real part of the complex number and get

$$H_r = k^2 \epsilon_{rpq} B_q z_p G F \frac{1}{R} \quad (35)$$

$$= -k^2 \epsilon_{rmn} B_m z_n \frac{e^{-ik(ct-R)}}{R^2} \quad (36)$$

so indeed

$$\mathbf{H}_n \approx -k^2 \epsilon_{rpq} \mathbf{B}_p \mathbf{z}_q \frac{\mathbf{e}^{-ik(ct-R)}}{\mathbf{R}^2}$$

Lets now look at the electric field

$$H_{n,m} = -k^2 \epsilon_{npq} B_p G \left[z_q F \frac{1}{R} \right]_{,m} \quad (37)$$

$$= -k^2 \epsilon_{npq} B_p G [z_q]_{,m} F \frac{1}{R} - k^2 \epsilon_{npq} B_p G z_q [F]_{,m} \frac{1}{R} - k^2 \epsilon_{npq} B_p G z_q F \left[\frac{1}{R} \right]_{,m} \quad (38)$$

$$= -k^2 \epsilon_{npm} B_p G F \frac{1}{R} - k^2 \epsilon_{npq} B_p G z_q F' R_{,m} \frac{1}{R} + k^2 \epsilon_{npq} B_p G z_q F \frac{R_{,m}}{R^2} \quad (39)$$

$$= -k^2 \epsilon_{npm} B_p G F \frac{1}{R} - k^2 \epsilon_{npq} B_p G z_q \left(\frac{ik}{R} - \frac{1}{R^2} \right) e^{ikR} \frac{z_m}{R} \frac{1}{R} + k^2 \epsilon_{npq} B_p G z_q F \frac{z_{,m}}{R^3} \quad (40)$$

$$= -k^2 \epsilon_{npm} B_p G F \frac{1}{R} - k^2 \epsilon_{npq} B_p G z_q k^2 \left(\frac{i}{kR} - \frac{1}{k^2 R^2} \right) e^{ikR} \frac{z_m}{R} \frac{1}{R} + k^2 \epsilon_{npq} B_p G z_q F \frac{z_{,m}}{R^3} \quad (41)$$

$$(42)$$

Again we can approximate by dropping the real part in $\left(\frac{i}{kR} - \frac{1}{k^2 R^2}\right)$ as $Rk \gg 2\pi$, so

$$H_{n,m} - k^2 \epsilon_{npm} B_p G F \frac{1}{R} - ik^3 \epsilon_{npq} B_p G z_q F z_m \frac{1}{R^2} + k^2 \epsilon_{npq} B_p G z_q F \frac{z_m}{R^3} \quad (43)$$

Lets' multiply (43) by ϵ_{rmn} Again we can approximate by dropping the real part in $\left(\frac{i}{kR} - \frac{1}{k^2 R^2}\right)$ as $Rk \gg 2\pi$, so

$$\epsilon_{rmn} H_{n,m} = \begin{cases} -k^2 \underbrace{\epsilon_{rmn} \epsilon_{npm}}_{=2\delta_{rp}} B_p G F \frac{1}{R} \\ -ik^3 \underbrace{\epsilon_{rmn} \epsilon_{npq}}_{=\delta_{pr}\delta_{mq}-\delta_{pm}\delta_{rq}} B_p G z_q F z_m \frac{1}{R^2} \\ +k^2 \underbrace{\epsilon_{rmn} \epsilon_{npq}}_{=\delta_{pr}\delta_{mq}-\delta_{pm}\delta_{rq}} B_p G z_q F \frac{z_m}{R^3} \end{cases} \quad (44)$$

$$= \begin{cases} -2k^2 B_r G F \frac{1}{R} \\ -ik^3 B_r G F \underbrace{z_m z_m}_{=R^2} \frac{1}{R^2} + ik^3 B_m z_m z_r G F \frac{1}{R^2} \\ +k^2 B_r \underbrace{z_m z_m}_{=R^2} G F \frac{1}{R^3} - k^2 B_m z_m z_r F G \frac{1}{R^3} \end{cases} \quad (45)$$

$$= \begin{cases} -k^2 B_r G F \frac{1}{R} - k^2 B_m z_m z_r F G \frac{1}{R^3} \\ -ik^3 B_r G F + ik^3 B_m z_m z_r G F \frac{1}{R^2} \end{cases} \quad (46)$$

Again we approximate by dropping the real part as $Rk \gg 2\pi$:

$$\epsilon_{rmn} H_{n,m} = -ik^3 (R^2 B_r + B_m z_m z_r) G F \frac{1}{R^2} \quad (47)$$

and as $\frac{1}{c} \partial_t E_r = \epsilon_{rmn} H_{n,m}$, and integrating along t we get

$$E_r = -ick^3 \left(R^2 B_r + B_m z_m z_r \frac{1}{R^2} \right) \frac{G}{-ick} F \frac{1}{R^2} \quad (48)$$

$$= k^2 (R^2 B_r + B_m z_m z_r) \frac{e^{-ikc(t-R)}}{R^3} \quad (49)$$

so indeed

$$\mathbf{E}_r \approx k^2 (\mathbf{R}^2 \mathbf{B}_r + \mathbf{B}_m \mathbf{z}_m \mathbf{z}_r) \frac{e^{-ikc(\mathbf{t}-\mathbf{R})}}{\mathbf{R}^3}$$



5.42 p238 - Exercise 15

In terms of the magnetic tensor H_{mn} , defined in **6.367**, show that, in curvilinear coordinates in space,

(a) The condition that λ^n be parallel to the magnetic field is

$$H_{mn}\lambda^n = 0$$

(b) The condition that μ_n be perpendicular to the magnetic field is

$$H_{mn}\mu_r + H_{nr}\mu_m + H_{rm}\mu_n = 0$$

(c) The square of the magnitude of the magnetic vector ($H^2 = H_r H^r$) is

$$H^2 = \frac{1}{2} H_{mn} H^{mn}$$

(a) $H_n \parallel \lambda_n$: Let's prove that first in Cartesian coordinate system. Suppose that H_n is parallel with the a curve tangent λ_n , then

$$H_n = H_0 \lambda_n \tag{1}$$

$$\times \epsilon_{rmn} \rightarrow H_{rm} = H_0 \epsilon_{rmn} \lambda_n \tag{2}$$

$$\times \lambda_m \rightarrow H_{rm} \lambda_m = H_0 \underbrace{\epsilon_{rmn} \lambda_n \lambda_m}_{=0} \tag{3}$$

$$\tag{4}$$

So in Cartesian coordinate system

$$H_{rm} \lambda_m = 0 \tag{5}$$

but this a tensor expression and becomes for a curvilinear system

$$H_{rm} \lambda^m = 0$$

◇

(b) $H_n \perp \mu_n$: We work directly in curvilinear coordinate systems.

$$H_n \perp \mu_n \Rightarrow H^r \mu_r = 0 \tag{6}$$

$$(6.364) \Rightarrow \frac{1}{2\sqrt{a}} \epsilon^{rmn} H_{mn} \mu_r = 0 \tag{7}$$

By renaming dummy indexes, (7) can also be written as

$$\frac{1}{2\sqrt{a}}\epsilon^{mrn}H_{rn}\mu_m = 0 \quad (8)$$

$$\frac{1}{2\sqrt{a}}\epsilon^{nrm}H_{rm}\mu_n = 0 \quad (9)$$

Summation of (7), (8), (9) gives

$$\epsilon^{rmn}H_{mn}\mu_r + \epsilon^{mrn}H_{rn}\mu_m + \epsilon^{nrm}H_{rm}\mu_n = 0 \quad (10)$$

$$\Leftrightarrow \epsilon^{rmn}H_{mn}\mu_r - \epsilon^{rmn}H_{rn}\mu_m + \epsilon^{rmn}H_{rm}\mu_n = 0 \quad (11)$$

$$(12)$$

and as H_{mn} is skew-symmetric:

$$\epsilon^{rmn}H_{mn}\mu_r + \epsilon^{rmn}H_{nr}\mu_m + \epsilon^{rmn}H_{rm}\mu_n = 0 \quad (13)$$

$$(14)$$

Hence, $\epsilon^{rmn}(H_{mn}\mu_r + H_{nr}\mu_m + H_{rm}\mu_n) = 0$ and conclude

$$H_{mn}\mu_r + H_{nr}\mu_m + H_{rm}\mu_n = 0$$

◇

(c) We work directly in curvilinear coordinate systems.

$$H^2 = H_r H^r \quad (15)$$

$$(6.364) \Rightarrow H^2 = \frac{\sqrt{a}}{2}\epsilon_{rmn}H^{mn}\frac{1}{2\sqrt{a}}\epsilon^{ruv}H_{uv} \quad (16)$$

$$= \frac{1}{4}(\delta_{mu}\delta_{nv} - \delta_{mv}\delta_{nu})H^{mn}H_{uv} \quad (17)$$

$$= \frac{1}{4}(H^{uv}H_{uv} - H^{vu}H_{uv}) \quad (18)$$

$$= \frac{1}{4}(H^{uv}H_{uv} + H^{uv}H_{uv}) \quad (19)$$

$$= \frac{1}{2}H^{uv}H_{uv} \quad (20)$$

◆

5.43 p238 - Exercise 16

Show that E_r and H_r are unchanged if, in equations **6.336**, ϕ_r and ψ are replaced by

$$\phi'_r = \phi_r + v_{,r}, \quad \psi' = \psi - \frac{1}{c} \partial_t v$$

where v is an arbitrary function of position and time. (This transformation of the electromagnetic potentials is called *gauge transformation*.) If v is any solution of the inhomogeneous equation

$$\frac{1}{c^2} \partial_t^2 v - v_{,mm} = \frac{1}{c} \partial_t \psi + \phi_{m,m}$$

show that, if ϕ_r and ψ satisfy **6.337** and **6.338** then ϕ'_r and ψ' satisfy equations of the form **6.339** and **6.340**

We have

$$\left\{ \begin{array}{ll} \text{6.336(a)} & E_r = -\frac{1}{c} \partial_t \phi_r - \psi_{,r} \\ \text{6.336(b)} & H_r = \epsilon_{rpq} \psi_{q,p} \end{array} \right. \quad (1)$$

So

$$E'_r = -\frac{1}{c} \partial_t \phi_r - \frac{1}{c} \partial_t v_{,r} - \psi_{,r} + \frac{1}{c} \partial_t v_{,r} \quad (2)$$

$$= -\frac{1}{c} \partial_t \phi_r - \psi_{,r} \quad (3)$$

$$= E_r \quad (4)$$

and

$$H'_r = \epsilon_{rpq} \phi_{q,p} + \underbrace{\epsilon_{rpq} v_{,qp}}_{=0} \quad (5)$$

$$= \epsilon_{rpq} \phi_{q,p} \quad (6)$$

$$= H_r \quad (7)$$

◇

We have

$$\left\{ \begin{array}{ll} \text{6.337} & \frac{1}{c^2} \partial_t^2 \phi_r + \frac{1}{c} \partial_t \psi_{,r} = \phi_{r,mm} - \phi_{m,mr} \\ \text{6.338} & \frac{1}{c} \partial_t \phi_{m,m} + \psi_{,mm} = 0 \end{array} \right. \quad (8)$$

and

$$\left\{ \begin{array}{ll} \mathbf{6.339(a)} & \frac{1}{c^2} \partial_t^2 \phi_r - \phi_{r,mm} = 0 \\ \mathbf{6.339(b)} & \frac{1}{c^2} \partial_t^2 \psi - \psi_{,mm} = 0 \\ \mathbf{6.340} & \frac{1}{c} \partial_t \psi + \phi_{m,m} = 0 \end{array} \right. \quad (9)$$

And let's indeed suppose that

$$\frac{1}{c^2} \partial_t^2 v - v_{,mm} = \frac{1}{c} \partial_t \psi + \phi_{m,m} \quad (10)$$

So for **6.339(a)** we get

$$\frac{1}{c^2} \partial_t^2 \phi_r' - \phi_{r,mm}' \quad (11)$$

$$= \frac{1}{c^2} \partial_t^2 \phi_r - \phi_{r,mm} + \underbrace{\frac{1}{c^2} \partial_t^2 v_{,r} - v_{,rmm}}_{=(10),r} \quad (12)$$

$$= \frac{1}{c^2} \partial_t^2 \phi_r - \phi_{r,mm} + \frac{1}{c} \partial_t \psi_{,r} + \phi_{m,rm} \quad (13)$$

$$= \underbrace{\frac{1}{c^2} \partial_t^2 \phi_r + \frac{1}{c} \partial_t \psi_{,r}}_{=(6.337)} - (\phi_{r,mm} + \phi_{m,rm}) \quad (14)$$

$$= (\phi_{r,mm} + \phi_{m,rm}) - (\phi_{r,mm} + \phi_{m,rm}) \quad (15)$$

$$= 0 \quad (16)$$

And for **6.339(b)** we get

$$\frac{1}{c^2} \partial_t^2 \psi' - \psi_{,mm}' \quad (17)$$

$$= \frac{1}{c^2} \partial_t^2 \psi - \psi_{,mm} - \frac{1}{c^3} \partial_t^3 v + \frac{1}{c} \partial_t v_{,mm} \quad (18)$$

$$= \frac{1}{c^2} \partial_t^2 \psi - \psi_{,mm} - \frac{1}{c} \partial_t \left(\underbrace{\frac{1}{c^2} \partial_t^2 v - v_{,mm}}_{=(10)} \right) \quad (19)$$

$$= \frac{1}{c^2} \partial_t^2 \psi - \psi_{,mm} - \frac{1}{c} \partial_t \left(\frac{1}{c} \partial_t \psi + \phi_{m,m} \right) \quad (20)$$

$$= \frac{1}{c^2} \partial_t^2 \psi - \frac{1}{c^2} \partial_t^2 \psi - \psi_{,mm} - \frac{1}{c} \partial_t \phi_{m,m} \quad (21)$$

$$= - \left(\underbrace{\psi_{,mm} + \frac{1}{c} \partial_t \phi_{m,m}}_{=(6.338)} \right) \quad (22)$$

$$= 0 \quad (23)$$

And for **6.340** we get

$$\frac{1}{c}\partial_t\psi' + \phi'_{m,m} \tag{24}$$

$$= \frac{1}{c}\partial_t\psi + \phi_{m,m} - \left(\underbrace{\frac{1}{c^2}\partial_t^2 v - v_{,mm}}_{=(10)} \right) \tag{25}$$

$$= \frac{1}{c}\partial_t\psi + \phi_{m,m} - \frac{1}{c}\partial_t\psi - \phi_{m,m} \tag{26}$$

$$= 0 \tag{27}$$



5.44 p239 - Exercise 17

Combining the vector potential ϕ_α ($\alpha = 1, 2, 3$) and the scalar potential ψ into a single 4-vector κ_r , given by

$$\kappa_\alpha = -\phi_\alpha, \quad \kappa_4 = \psi$$

show that equations **6.336**, **6.337** and **6.338**, can be written in the relativistic form

$$F_{mn} = \kappa_{m,n} - \kappa_{n,m}$$

$$g^{mn} \kappa_{r|mn} - g^{mn} \kappa_{m|rn} = 0$$

where F_{mn} is as in **6.371** and g^{mn} as in **6.376**. Show further that equations **6.339** and **6.340** become

$$g^{mn} \kappa_{r|mn} = 0, \quad g^{mn} \kappa_{m|n} = 0$$

Show also that the gauge transformation of the preceding exercise can be written

$$\kappa'_r = \kappa_r - v_{,r}$$

What we know

$$\left\{ \begin{array}{ll} \mathbf{6.371(a)} & F_{\alpha\beta} = H_{\alpha\beta}, \quad F_{\alpha 4} = -F_{4\alpha} = E_\alpha, \quad F_{44} = 0 \\ \mathbf{6.376(b)} & g^{\alpha\beta} = a^{\alpha\beta}, \quad g_{\alpha 4} = 0, \quad g_{44} = -1 \\ \mathbf{6.336(a)} & E_r = -\frac{1}{c} \partial_t \phi_r - \psi_{,r} \\ \mathbf{6.336(b)} & H_r = \epsilon_{rpq} \phi_{q,p} \\ \mathbf{6.337} & \frac{1}{c^2} \partial_t^2 \phi_r + \frac{1}{c} \partial_t \psi_{,r} = \phi_{r,mm} - \phi_{m,mr} \\ \mathbf{6.338} & \frac{1}{c} \partial_t \phi_{m,m} + \psi_{,mm} = 0 \\ \mathbf{6.367} & H_{rm} = \epsilon_{rmn} H_n, \quad H_r = \frac{1}{2} \epsilon_{rmn} H_{mn} \end{array} \right. \quad (1)$$

Then

$$\mathbf{6.336(b)} \times \epsilon_{ruv}: \quad H_{uv} = (\delta_{up} \delta_{vq} - \delta_{uq} \delta_{vp}) \phi_{q,p} \quad (2)$$

$$= \phi_{v,u} - \phi_{u,v} \quad (3)$$

So for $(u, v) = (\alpha, \beta)$ we have

$$H_{\alpha\beta} = \phi_{\beta,\alpha} - \phi_{\alpha,\beta} \quad (4)$$

$$F_{\alpha\beta} = H_{\alpha\beta} = -(\phi_{\alpha,\beta} - \phi_{\beta,\alpha}) \quad (5)$$

$$= \kappa_{\alpha,\beta} - \kappa_{\beta,\alpha} \quad (6)$$

Consider F_{44} and $\kappa_4 = \psi$.

So,

$$F_{44} = \kappa_{44} - \kappa_{44} \quad (7)$$

$$= 0 \quad (8)$$

So, indeed $F_{44} = 0$

Consider $F_{\alpha 4}$.

$$6.336(a): \quad F_{\alpha 4} = -\frac{1}{c} \partial_t \phi_\alpha - \psi_{,\alpha} \quad (9)$$

$$= \frac{1}{c} \partial_t \kappa_\alpha - \kappa_{4,\alpha} \quad (10)$$

$$(11)$$

But $\frac{1}{c} \partial_t \kappa_\alpha = \frac{\partial \kappa_\alpha}{\partial ct} = \kappa_{4\alpha}$

So,

$$F_{\alpha 4} = \kappa_{\alpha,4} - \kappa_{4,\alpha} \quad (12)$$

and conclude that (6), (8) and (12) can be expressed by the general formula

$$F_{mn} = \kappa_{m,n} - \kappa_{n,m}$$

◇

We have

$$6.337: \quad \frac{1}{c^2} \partial_t^2 \phi_r + \frac{1}{c} \partial_t \psi_{,r} = \phi_{r,mm} - \phi_{m,mr} \quad (13)$$

The left term can be expressed as

$$\frac{\partial^2 \phi_r}{\partial (ct)^2} + \frac{\partial^2 \psi_r}{\partial (ct)} = \phi_{r,44} + \psi_{,r4} \quad (14)$$

Hence (13) becomes

$$\phi_{\alpha,44} + \psi_{,\alpha 4} = \phi_{\alpha,\beta\beta} - \phi_{\beta,\beta\alpha} \quad (15)$$

$$\Rightarrow -\kappa_{\alpha,44} + \kappa_{4,\alpha 4} = -\kappa_{\alpha,\beta\beta} + \kappa_{\beta,\beta\alpha} \quad (16)$$

$$\Rightarrow \kappa_{\alpha,\beta\beta} - \kappa_{\alpha,44} + \kappa_{4,4\alpha} - \kappa_{\beta,\beta\alpha} = 0 \quad (17)$$

and using the metric g^{mn} we can write this as

$$g^{mn}\kappa_{\alpha|mn} - g^{mn}\kappa_{m|\alpha n} = 0 \quad (18)$$

This is true as (18) is a tensor expression and if true in a particular coordinate system it must be true all coordinate systems (see the discussion page 62 of the book.)

Yet, this yields only for $\alpha = (1, 2, 3)$ and we still have to prove that this expression is valid for $\alpha = 4$

We have

$$6.338: \quad \frac{1}{c}\partial_t\phi_{m,m} + \psi_{,mm} = 0 \quad (19)$$

The left term can be expressed as

$$\frac{\partial\phi_{\alpha,\alpha}}{\partial(ct)} + \psi_{,\alpha\alpha} = 0 \quad (20)$$

$$\Leftrightarrow \phi_{\alpha,\alpha 4} + \psi_{,\alpha\alpha} = 0 \quad (21)$$

$$\Leftrightarrow \kappa_{\alpha,\alpha 4} - \kappa_{4,\alpha\alpha} = 0 \quad (22)$$

and using the metric g^{mn} we can write this as

$$g^{mn}\kappa_{4|mn} - g^{mn}\kappa_{m|n4} = 0 \quad (23)$$

So (18) and (24) can be written as

$$g^{mn}\kappa_{r|mn} - g^{mn}\kappa_{m|nr} = 0$$

◇

What about **6.339** and **6.340**

$$6.339(a): \quad \frac{1}{c^2} \partial_t^2 \phi_r - \phi_{r,mm} = 0 \quad (24)$$

$$\Leftrightarrow \quad \frac{\partial^2 \phi_\alpha}{\partial(ct)^2} - \phi_{\alpha,\beta\beta} = 0 \quad (25)$$

$$\Leftrightarrow \quad \phi_{\alpha,44} - \phi_{\alpha,\beta\beta} = 0 \quad (26)$$

$$\Leftrightarrow \quad \kappa_{\alpha,44} - \kappa_{\alpha,\beta\beta} = 0 \quad (27)$$

$$6.339(b): \quad \frac{1}{c^2} \partial_t^2 \psi - \psi_{,mm} = 0 \quad (28)$$

$$\Leftrightarrow \quad \frac{\partial^2 \psi}{\partial(ct)^2} - \psi_{,\beta\beta} = 0 \quad (29)$$

$$\Leftrightarrow \quad \psi_{,44} - \psi_{,\beta\beta} = 0 \quad (30)$$

$$\Leftrightarrow \quad \kappa_{4,44} - \kappa_{4,\beta\beta} = 0 \quad (31)$$

Again we can write (28) and (31) as

$$g^{mn} \kappa_{r|mn} = 0$$

$$6.340: \quad \frac{1}{c} \partial_t \psi + \phi_{m,m} = 0 \quad (32)$$

$$\Leftrightarrow \quad \frac{\partial \psi}{\partial(ct)} - \phi_{\beta,\beta} = 0 \quad (33)$$

$$\Leftrightarrow \quad \psi_{,4} + \phi_{\beta,\beta} = 0 \quad (34)$$

$$\Leftrightarrow \quad \kappa_{4,4} - \kappa_{\beta,\beta} = 0 \quad (35)$$

Hence (35) can be written as

$$g^{mn} \kappa_{m|n} = 0$$

◇

For the gauge transformation in the preceding exercise we had the condition

$$\frac{1}{c^2} \partial_t^2 v - v_{,mm} = \frac{1}{c} \partial_t \psi + \phi_{m,m} \quad (36)$$

$$\Leftrightarrow \quad \frac{\partial^2 v}{\partial(ct)^2} - v_{,mm} = \frac{\partial \psi}{\partial(ct)} + \phi_{m,m} \quad (37)$$

$$\Leftrightarrow \quad v_{,44} - v_{,\beta\beta} = \kappa_{4,4} - \kappa_{\beta,\beta} \quad (38)$$

Substituting $\kappa_r = \kappa'_r + v_{,r}$, one gets for (38)

$$v_{,44} - v_{,\beta\beta} = \kappa'_{4,4} + v_{,44} - \kappa'_{\beta,\beta} - v_{,\beta\beta} \quad (39)$$

$$\Leftrightarrow \quad \kappa'_{4,4} - \kappa'_{\beta,\beta} = 0 \quad (40)$$

So the condition (35) is respected and the gauge transformation can be expressed by $\kappa'_r = \kappa_r - v_{,r}$

◆

5.45 p239 - Exercise 18

Using homogeneous coordinates z_r (z_1, z_2, z_3 being rectangular Cartesians in space and $z_4 = ict = ix^4$), and defining

$$\hat{F}_{mn} = \frac{1}{2} \epsilon_{mnrs} F_{rs}$$

show that the complete set of Maxwell's equations **6.378** reads

$$F_{rm,m} = 0, \quad \hat{F}_{rm,m} = 0$$

In exercise page 231 we already proved that for this kind of coordinates:

$$F_{rm,m} = 0$$

◇

From this same exercise page 231, we also know that

$$\mathbf{6.378(a)} \quad F_{rm,n} + F_{mn,r} + F_{nr,m} = 0 \quad (1)$$

From the definition of \hat{F}_{rm} :

$$\hat{F}_{rm,m} = \frac{1}{2} \epsilon_{rmuv} F_{uv,m} \quad (2)$$

Playing with the dummy indexes:

$$\hat{F}_{rm,m} = \frac{1}{2} \epsilon_{rumv} F_{mv,u} \quad (3)$$

$$\hat{F}_{rm,m} = \frac{1}{2} \epsilon_{rvum} F_{um,v} \quad (4)$$

Adding (2), (3), (4):

$$3\hat{F}_{rm,m} = \frac{1}{2} (\epsilon_{rmuv} F_{uv,m} + \epsilon_{rumv} F_{mv,u} + \epsilon_{rvum} F_{um,v}) \quad (5)$$

$$= \frac{1}{2} (\epsilon_{rmuv} F_{uv,m} - \epsilon_{rmuv} F_{mv,u} - \epsilon_{rmuv} F_{um,v}) \quad (6)$$

$$= \frac{1}{2} \epsilon_{rmuv} (F_{uv,m} - F_{mv,u} - F_{um,v}) \quad (7)$$

$$= \frac{1}{2} \epsilon_{rmuv} \left(\underbrace{F_{uv,m} + F_{vm,u} + F_{mu,v}}_{=0} \right) \quad (8)$$

So we conclude that

$$\hat{F}_{rm,m} = 0$$

◆

Relative tensors, ideas of volume,
Green-Stokes theorems.

7.1 p241 - Exercise

If b_{rs} is an absolute tensor, show that the determinant $|b_{rs}|$ is a relative invariant of weight 2. What are the tensor characters of $|c^{rs}|$ and $|f_s^r|$?

As b_{rs} is an absolute tensor, we have

$$b'_{uv} = b_{rs} \frac{\partial x^r}{\partial x'^u} \frac{\partial x^s}{\partial x'^v} \quad (1)$$

Hence,

$$|b'_{uv}| = |b_{rs}| \left| \frac{\partial x^r}{\partial x'^u} \right| \left| \frac{\partial x^s}{\partial x'^v} \right| \quad (2)$$

and as $J = \left| \frac{\partial x^k}{\partial x'^s} \right|$ we get

$$|b'_{uv}| = J^2 |b_{rs}| \quad (3)$$

Conclusion, $|b_{rs}|$ is a relative invariant of weight 2.

◇

As c^{rs} is an absolute tensor, we have

$$c'^{uv} = c^{rs} \frac{\partial x'^u}{\partial x^r} \frac{\partial x'^v}{\partial x^s} \quad (4)$$

Hence,

$$|c'^{uv}| = |c^{rs}| \left| \frac{\partial x'^u}{\partial x^r} \right| \left| \frac{\partial x'^v}{\partial x^s} \right| \quad (5)$$

and as $J^{-1} = \left| \frac{\partial x'^s}{\partial x^k} \right|$ we get

$$|c'^{uv}| = J^{-2} |c^{rs}| \quad (6)$$

Conclusion, $|c^{rs}|$ is a relative invariant of weight -2 .

◇

As f_s^r is an absolute tensor, we have

$$f_v'^u = f_s^r \frac{\partial x'^u}{\partial x^r} \frac{\partial x^s}{\partial x'^v} \quad (7)$$

Hence,

$$\left| f_v'^u \right| = \left| f_s^r \right| \left| \frac{\partial x'^u}{\partial x^r} \right| \left| \frac{\partial x^s}{\partial x'^v} \right| \quad (8)$$

and we get

$$\left| f_v'^u \right| = J J^{-1} \left| f_s^r \right| \quad (9)$$

Conclusion, $|f_s^r|$ is an absolute invariant tensor .



7.2 p242 - Exercise

Show that, in three dimensions, the only non-vanishing components of δ_{rs}^{kl} are

$$\delta_{23}^{23} = \delta_{32}^{32} = \delta_{31}^{31} = \delta_{13}^{13} = \delta_{12}^{12} = \delta_{21}^{21} = 1$$

$$\delta_{32}^{23} = \delta_{23}^{32} = \delta_{13}^{31} = \delta_{31}^{13} = \delta_{21}^{12} = \delta_{12}^{21} = -1$$

This is easily seen. If $(k, l), (r, s)$ are considered as sets, then $\delta_{rs}^{kl} \neq 0 \Leftrightarrow (k, l) \neq (r, s)$. And $\delta_{rs}^{kl} = 1 \Leftrightarrow k = r \wedge l = s$ and on the opposite $\delta_{rs}^{kl} = -1 \Leftrightarrow k = s \wedge l = r$



7.3 p243 - Exercise

Show that equations **5.231** and **6.128** can be written as follows:

$$M_{rs} = \delta_{rs}^{kl} z_k F_l$$

$$\omega_{rs} = \frac{1}{2} \delta_{rs}^{kl} v_{l,k}$$

$$(5.231) \quad M_{rs} = \epsilon_{rsn} M_n = z_r F_s - z_s F_r \quad (1)$$

In this expression $M_{rs} = 0$ when $r = s$, but this is also the case with δ_{rs}^{kl} .

In $M_{rs} = \delta_{rs}^{kl} z_k F_l$ we see that there is no contribution in the summation when $k = l$. The only contribution being those for which $k = r \wedge l = s$ (positive contribution) \vee $k = s \wedge l = r$ (negative contribution), hence

$$\delta_{rs}^{kl} z_k F_l \Leftrightarrow z_r F_s - z_s F_r$$

◇

$$(6.128) \quad \omega_{rs} = \frac{1}{2} (v_{s,r} - v_{r,s}) \quad (2)$$

The same arguments of the previous case apply to this case (a way to see this is to represent symbolically, $z_r F_s$ and $v_{s,r}$ by T_{rs})

◆

7.4 p243 - Exercise

If $T_{k_1 k_2 \dots k_M}$ is completely skew-symmetric, determine

$$\delta_{s_1 s_2 \dots s_M}^{k_1 k_2 \dots k_M} T_{k_1 k_2 \dots k_M}$$

$\delta_{s_1 s_2 \dots s_M}^{k_1 k_2 \dots k_M} T_{k_1 k_2 \dots k_M}$ is a sum of $M!$ terms: the first of these is $T_{s_1 s_2 \dots s_M}$; the other terms are obtained from it by permuting the subscripts and a minus sign is attached if the permutation is odd. Since $T_{s_1 s_2 \dots s_M}$ is completely skew-symmetric, each of the $M!$ terms equals $\pm T_{s_1 s_2 \dots s_M}$. Hence,

$$\delta_{s_1 s_2 \dots s_M}^{k_1 k_2 \dots k_M} T_{k_1 k_2 \dots k_M} = M! T_{s_1 s_2 \dots s_M}$$



7.5 p245 - Exercise

Show that $\epsilon^{r_1 r_2 \dots r_N} \epsilon_{r_1 r_2 \dots r_N} = N!$.

First note that $\text{sign}(\epsilon^{r_1 r_2 \dots r_N}) = \text{sign}(\epsilon_{r_1 r_2 \dots r_N})$ so that each term in the summation is always +1.

There are N choices to chose from for r_1 , $N - 1$ for r_2 , etc. and only one for r_N . And so $\epsilon^{r_1 r_2 \dots r_N} \epsilon_{r_1 r_2 \dots r_N} = N!$



7.6 p245 - Clarification to 7.113

$$\epsilon^{k_1 \dots k_M r_1 \dots r_{N-M}} \epsilon_{s_1 \dots s_M r_1 \dots r_{N-M}} = (N - M)! \delta_{s_1 \dots s_M}^{k_1 \dots k_M}$$

This can be seen as followed.

As the permutation $(r_1 \dots r_{N-M})$ is the same for both covariant and contravariant permutation symbols, the product $\epsilon^{k_1 \dots k_M r_1 \dots r_{N-M}} \epsilon_{s_1 \dots s_M r_1 \dots r_{N-M}}$ for a fixed permutation $(r_1 \dots r_{N-M})$ (i.e. no summation on repeated indexes) will be determined by $\delta_{s_1 \dots s_M}^{k_1 \dots k_M}$. Indeed, the difference in "oddness" between $(k_1 \dots k_M r_1 \dots r_{N-M})$ and $(s_1 \dots s_M r_1 \dots r_{N-M})$ is only determined by the difference in "oddness" between $(k_1 \dots k_M r_1)$ and $(s_1 \dots s_M)$. So each term in the summation has the same contribution, i.e.; $\delta_{s_1 \dots s_M}^{k_1 \dots k_M}$.

There are M choices to chose from for r_1 , $M - 1$ for r_2 , etc. and only one for r_M . And so

$$\epsilon^{k_1 \dots k_M r_1 \dots r_{N-M}} \epsilon_{s_1 \dots s_M r_1 \dots r_{N-M}} = (N - M)! \delta_{s_1 \dots s_M}^{k_1 \dots k_M}$$



7.7 p247 - Exercise

If T_{rs} is an absolute skew-symmetric tensor in a 4-space, show that

$$T_{14}T_{23} + T_{24}T_{31} + T_{34}T_{12}$$

is a tensor density

Be $P = T_{14}T_{23} + T_{24}T_{31} + T_{34}T_{12}$, we can write this as $P = \frac{1}{8}\delta_{1234}^{ijmn}T_{ij}T_{mn}$

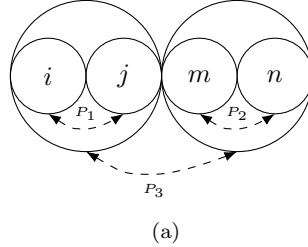


Figure 7.1: Permutations

The factor $\frac{1}{8}$ is explained by the fact that there are 2^3 possible permutations in the i, j, m, n indexes i.e. 2×2 for the permutations P_1 and P_2 and again 2 for the permutation P_3 . Note that a single permutation P_1 or P_2 changes the sign of $T_{ij}T_{mn}$ but also changes the sign of δ_{1234}^{ijmn} , so the combined sign doesn't change. A double permutation P_1 and P_2 changes the sign of T_{ij} and T_{mn} resulting in an unchanged sign of $T_{ij}T_{mn}$ but also δ_{1234}^{ijmn} is unchanged because of the double permutation. Finally P_3 has no effect, nor on $T_{ij}T_{mn}$ nor on δ_{1234}^{ijmn} . So we have 8 repetitions for the same set i, j, m, n . So we have,

$$P = \frac{1}{8}\delta_{1234}^{ijmn}T_{ij}T_{mn} \quad (1)$$

$$= \frac{1}{8}\epsilon^{ijmn}T_{ij}T_{mn} \quad (2)$$

From this follows immediately as ϵ^{ijmn} is a relative tensor of weight 1 and T_{ij} an absolute tensor (i.e. a relative tensor of weight 0) that P is a relative tensor of weight 1 i.e. a density.



7.8 p247 - Exercise

Show that, for rectangular Cartesian coordinates, the vorticity tensor and the vorticity vector of a fluid are duals (cf. **6.130**).

6.130:

$$\omega_r = \frac{1}{2} \epsilon_{rmn} \omega_{mn}, \quad \omega_{mn} = \epsilon_{rmn} \omega_r \quad (1)$$

Put $\hat{T}^r = \omega_r$ and $T_{mn} = \omega_{mn}$ then the expressions in (1) can be expressed as (considering that the covariant and contravariant expressions are identical in rectangular Cartesian coordinates)

$$\hat{T}^r = \frac{1}{(3-2)!} \epsilon^{mnr} T_{mn}, \quad T_{mn} = \epsilon_{rmn} \hat{T}^r \quad (2)$$

which are exactly the general definitions **7.121** and **7.122** (with $N = 3$ and $M = 2$) for dual tensors.



7.9 p250 - Exercise

Show that

$$\eta_{r_1 \dots r_N} = \epsilon(a) a_{r_1 s_1} \dots a_{r_N s_N} \eta^{s_1 \dots s_N}$$

$$\eta^{r_1 \dots r_N} = \epsilon(a) a^{r_1 s_1} \dots a^{r_N s_N} \eta_{s_1 \dots s_N}$$



7.10 p252 - Exercise

Using Riemannian coordinates, prove that **7.216** $\epsilon_{r_1 \dots r_N | k} = \epsilon^{r_1 \dots r_N}_{| k} = 0$ $\eta_{r_1 \dots r_N | k} = \eta^{r_1 \dots r_N}_{| k} = 0$



7.11 p252 - Exercise

Prove that if T^n is a relative vector of weight W then,

$$\mathbf{7.220} \quad T^n|_n = (\epsilon(a)a)^{\frac{1}{2}(W-1)} \frac{\partial}{\partial x^n} \left[(\epsilon(a)a)^{\frac{1}{2}(1-W)} T^n \right]$$



7.12 p255 - Clarification

$$\mathbf{7.304} \quad \Delta^{k_1 \dots k_M} = \delta_{s_1 \dots s_M}^{k_1 \dots k_M} \Delta_{(1)} x^{s_1} \dots \Delta_{(M)} x^{s_M}$$

Using **7.303** and noting that a permutation of columns in the matrix changes or not the sign of its determinant depending on the sign of the permutation, we can write

$$\Delta^{k_1 \dots k_M} = \begin{vmatrix} \Delta_{(1)} x^{k_1} & \Delta_{(1)} x^{k_2} & \dots & \Delta_{(1)} x^{k_M} \\ \Delta_{(2)} x^{k_1} & \Delta_{(2)} x^{k_2} & \dots & \Delta_{(2)} x^{k_M} \\ \vdots & \vdots & \vdots & \vdots \\ \Delta_{(M)} x^{k_1} & \Delta_{(M)} x^{k_2} & \dots & \Delta_{(M)} x^{k_M} \end{vmatrix} \quad (1)$$

$$= \epsilon^{k_1 k_2 \dots k_M} \begin{vmatrix} \Delta_{(1)} x^1 & \Delta_{(1)} x^2 & \dots & \Delta_{(1)} x^M \\ \Delta_{(2)} x^1 & \Delta_{(2)} x^2 & \dots & \Delta_{(2)} x^M \\ \vdots & \vdots & \vdots & \vdots \\ \Delta_{(M)} x^1 & \Delta_{(M)} x^2 & \dots & \Delta_{(M)} x^M \end{vmatrix} \quad (2)$$

And using **4.313** : $|A_{pq}| = \epsilon_{s_1 s_2 \dots s_M} A_{1s_1} A_{2s_2} \dots A_{Ms_M}$:

$$\Delta^{k_1 \dots k_M} = \underbrace{\epsilon^{k_1 k_2 \dots k_M} \epsilon_{s_1 s_2 \dots s_M}}_{\text{see (7.114)}} \Delta_{(1)} x^{s_1} \Delta_{(2)} x^{s_2} \dots \Delta_{(M)} x^{s_M} \quad (3)$$

$$= \delta_{s_1 \dots s_M}^{k_1 \dots k_M} \Delta_{(1)} x^{s_1} \Delta_{(2)} x^{s_2} \dots \Delta_{(M)} x^{s_M} \quad (4)$$



7.13 p255 - Exercise

Show that **7.305** may be written in the equivalent form

$$d\tau_{(M)}^{k_1 \dots k_m} = \epsilon^{\beta_1 \dots \beta_M} d_{(\beta_1)} x^{k_1} \dots d_{(\beta_M)} x^{k_M}$$

The determinant of a matrix and its transpose are equal.

Hence we can rewrite **7.305** $\delta_{s_1 \dots s_M}^{k_1 \dots k_M} d_{(1)} x^{s_1} \dots d_{(M)} x^{s_M}$ as

$$d\tau_{(M)}^{k_1 \dots k_m} = \delta_{k_1 \dots k_M}^{s_1 \dots s_M} d_{(s_1)} x^1 \dots d_{(s_M)} x^M \quad (1)$$

In order to be consistent with the notation we replace the s_i by α_i as the summation occurs along the constants $c^{(i)}$

$$d\tau_{(M)}^{k_1 \dots k_m} = \delta_{k_1 \dots k_M}^{\alpha_1 \dots \alpha_M} d_{(\alpha_1)} x^1 \dots d_{(\alpha_M)} x^M \quad (2)$$

Given the set $\{k_1, k_2, \dots, k_M\}$ we can represent the sequence $\{1, 2, \dots, M\}$ by $\{k_j, k_m, \dots, k_M, \dots, k_n\}$ (imagine that $k_j = 1, k_m = 2, \dots$ etc.). We rewrite (2) as

$$d\tau_{(M)}^{k_1 k_2 \dots k_m} = (\theta_\alpha) \delta_{12 \dots M}^{\alpha_1 \dots \alpha_M} d_{(\alpha_1)} x^{k_j} d_{(\alpha_2)} x^{k_m} \dots d_{(\alpha_M)} x^{k_n} \quad (3)$$

where

$$\theta_\alpha = \epsilon_{k_1 k_2 \dots k_M} \quad (4)$$

(a permutation in the lower indexes of the generalized Kronecker deltas symbol will invert the sign depending on the 'oddness' of the permutation). Let's rearrange the product $d_{(\alpha_1)} x^{k_j} d_{(\alpha_2)} x^{k_m} \dots d_{(\alpha_M)} x^{k_n}$ so that the indexes k_i are naturally ordered

$$d\tau_{(M)}^{k_1 k_2 \dots k_m} = (\theta_\alpha) \delta_{12 \dots M}^{\alpha_1 \dots \alpha_M} d_{(\alpha_r)} x^{k_1} d_{(\alpha_n)} x^{k_2} \dots d_{(\alpha_1)} x^{k_n} \dots d_{(\alpha_s)} x^{k_M} \quad (5)$$

and changing the order in the upper indexes of the general Kroneckers delta's:

$$d\tau_{(M)}^{k_1 k_2 \dots k_m} = (\theta_\alpha)(\theta_k) \delta_{12 \dots M}^{\alpha_r \alpha_n \dots \alpha_s} d_{(\alpha_r)} x^{k_1} d_{(\alpha_n)} x^{k_2} \dots d_{(\alpha_1)} x^{k_n} \dots d_{(\alpha_s)} x^{k_M} \quad (6)$$

where $\theta_k = \pm 1$ depending on the 'oddness' of the permutation needed to go from $\{\alpha_1 \dots \alpha_M\}$ to $\{\alpha_r \alpha_n \dots \alpha_s\}$.

As we can see in figure 7.2, it's no hard to see that

$$\theta_k = \theta_\alpha \quad (7)$$

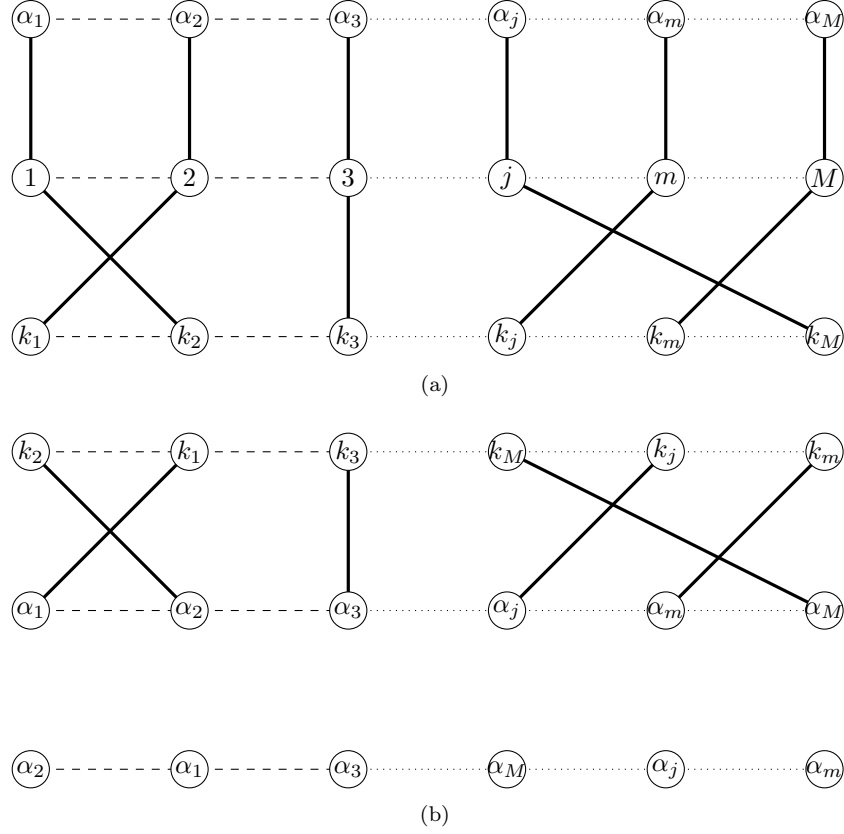


Figure 7.2: Permutations

Indeed suppose, as in the example (a), $k_1 = 2, k_2 = 1, k_3 = 3, \dots, k_j = m, \dots, k_m = j, \dots$ etc., so we get a sequence $\{k_2, k_1, k_3, \dots, k_m, \dots, k_j, \dots\}$ as illustrated in (b). But to have - with this sequence - an equivalent expression of $d\tau_{(M)}^{k_1 k_2 \dots k_m} = (\theta_\alpha) \delta_{12 \dots M}^{\alpha_1 \dots \alpha_M} d_{(\alpha_1)} x^{k_j} d_{(\alpha_2)} x^{k_m} \dots d_{(\alpha_M)} x^{k_n}$, we need to make an equivalent permutation so that α_r gets in the same position as k_r , resulting in a new sequence $\{\alpha_2, \alpha_1, \alpha_3, \dots, \alpha_M, \dots, \alpha_j, \alpha_m\}$.

The number of permutations to generate θ_α and θ_k are identical resulting in $\theta_\alpha \theta_k = 1$. So (6) can be rewritten (noting that the α_r are dummy indexes and that we are free to rename them so that $r = 1, n = 2, \dots$)

$$d\tau_{(M)}^{k_1 k_2 \dots k_m} = \delta_{12 \dots M}^{\beta_1 \beta_2 \dots \beta_M} d_{(\beta_1)} x^{k_1} d_{(\beta_2)} x^{k_2} \dots d_{(\beta_n)} x^{k_n} \dots d_{(\beta_M)} x^{k_M} \quad (8)$$

Finally, using **7.114**

$$d\tau_{(M)}^{k_1 k_2 \dots k_m} = \underbrace{\epsilon_{12 \dots M}}_{=1} \epsilon^{\beta_1 \beta_2 \dots \beta_M} d_{(\beta_1)} x^{k_1} d_{(\beta_2)} x^{k_2} \dots d_{(\beta_n)} x^{k_n} \dots d_{(\beta_M)} x^{k_M} \quad (9)$$

$$= \epsilon^{\beta_1 \beta_2 \dots \beta_M} d_{(\beta_1)} x^{k_1} d_{(\beta_2)} x^{k_2} \dots d_{(\beta_n)} x^{k_n} \dots d_{(\beta_M)} x^{k_M} \quad (10)$$



7.14 p257 - Exercise

Let x^k be rectangular Cartesian coordinates in Euclidean 3-space. Introduce polar coordinates r, θ, ϕ and consider the surface of the sphere $r = a$. On this sphere form the infinitesimal 2-cell with corners (θ, ϕ) , $(\theta + d\theta, \phi)$, $(\theta, \phi + d\phi)$, $(\theta + d\theta, \phi + d\phi)$. Determine the extension of this cell and interpret the rectangular components. In particular, show that the three independent components of the extension are (apart from the sign) equal to the areas obtained by normal projection of the cell onto the three rectangular planes. Does this interpretation remain valid if the sphere is replaced by some other surface?

We use **7.312**:

$$d\tau_{(2)}^{k_1 k_2} = \epsilon^{\alpha_1 \alpha_2} \frac{\partial x^{k_1}}{\partial y^{\alpha_1}} \frac{\partial x^{k_2}}{\partial y^{\alpha_2}} |d_{(\beta)} y^\gamma| \quad (1)$$

with $(y^1, y^2) = (\theta, \phi)$ giving if we take $f^{(i)} = c^{(i)}$ as $\theta = c^{(1)}$, $\phi = c^{(2)}$:

$$|d_{(\beta)} y^\gamma| = \begin{vmatrix} d_{(1)} y^1 & d_{(1)} y^2 \\ d_{(2)} y^1 & d_{(2)} y^2 \end{vmatrix} \quad (2)$$

$$= \begin{vmatrix} d\theta & 0 \\ 0 & d\phi \end{vmatrix} \quad (3)$$

$$= d\theta d\phi \quad (4)$$

We also have

$$\begin{cases} x = a \sin \theta \cos \phi \\ y = a \sin \theta \sin \phi \\ z = a \cos \theta \end{cases} \quad (5)$$

$$(6)$$

giving

$$\begin{cases} \frac{\partial x}{\partial \theta} = a \cos \theta \cos \phi \\ \frac{\partial x}{\partial \phi} = -a \sin \theta \sin \phi \\ \frac{\partial y}{\partial \theta} = a \cos \theta \sin \phi \\ \frac{\partial y}{\partial \phi} = a \sin \theta \cos \phi \\ \frac{\partial z}{\partial \theta} = -a \sin \theta \\ \frac{\partial z}{\partial \phi} = 0 \end{cases} \quad (7)$$

$$(8)$$

and get

$$d\tau_{(2)}^{xy} = \underbrace{\epsilon^{11}}_{=0} \frac{\partial x}{\partial \theta} \frac{\partial y}{\partial \theta} d\theta d\phi + \epsilon^{12} \frac{\partial x}{\partial \theta} \frac{\partial y}{\partial \phi} d\theta d\phi + \epsilon^{21} \frac{\partial x}{\partial \phi} \frac{\partial y}{\partial \theta} d\theta d\phi + \underbrace{\epsilon^{22}}_{=0} \frac{\partial x}{\partial \phi} \frac{\partial y}{\partial \phi} d\theta d\phi \quad (9)$$

$$= a^2 \cos \theta \cos \phi \sin \theta \cos \phi d\theta d\phi + a^2 \sin \theta \sin \phi \cos \theta \sin \phi d\theta d\phi \quad (10)$$

$$= a^2 \cos \theta \sin \theta d\theta d\phi \quad (11)$$

$$d\tau_{(2)}^{yx} = -a^2 \cos \theta \sin \theta d\theta d\phi \quad (12)$$

$$d\tau_{(2)}^{xz} = \underbrace{\epsilon^{11}}_{=0} \frac{\partial x}{\partial \theta} \frac{\partial z}{\partial \theta} d\theta d\phi + \epsilon^{12} \frac{\partial x}{\partial \theta} \underbrace{\frac{\partial z}{\partial \phi}}_{=0} d\theta d\phi + \epsilon^{21} \frac{\partial x}{\partial \phi} \frac{\partial z}{\partial \theta} d\theta d\phi + \underbrace{\epsilon^{22}}_{=0} \frac{\partial x}{\partial \phi} \frac{\partial z}{\partial \phi} d\theta d\phi \quad (13)$$

$$= -a^2 \sin^2 \theta \sin \phi d\theta d\phi \quad (14)$$

$$d\tau_{(2)}^{zx} = a^2 \sin^2 \theta \sin \phi d\theta d\phi \quad (15)$$

$$d\tau_{(2)}^{yz} = \underbrace{\epsilon^{11}}_{=0} \frac{\partial y}{\partial \theta} \frac{\partial z}{\partial \theta} d\theta d\phi + \epsilon^{12} \frac{\partial y}{\partial \theta} \underbrace{\frac{\partial z}{\partial \phi}}_{=0} d\theta d\phi + \epsilon^{21} \frac{\partial y}{\partial \phi} \frac{\partial z}{\partial \theta} d\theta d\phi + \underbrace{\epsilon^{22}}_{=0} \frac{\partial y}{\partial \phi} \frac{\partial z}{\partial \phi} d\theta d\phi \quad (16)$$

$$= a^2 \sin^2 \theta \cos \phi d\theta d\phi \quad (17)$$

$$d\tau_{(2)}^{zy} = -a^2 \sin^2 \theta \cos \phi d\theta d\phi \quad (18)$$

$$d\tau_{(2)}^{xx} = \underbrace{\epsilon^{11}}_{=0} \frac{\partial x}{\partial \theta} \frac{\partial x}{\partial \theta} d\theta d\phi + \epsilon^{12} \frac{\partial x}{\partial \theta} \frac{\partial x}{\partial \phi} d\theta d\phi + \epsilon^{21} \frac{\partial x}{\partial \phi} \frac{\partial x}{\partial \theta} d\theta d\phi + \underbrace{\epsilon^{22}}_{=0} \frac{\partial x}{\partial \phi} \frac{\partial x}{\partial \phi} d\theta d\phi \quad (19)$$

$$= 0 \quad (20)$$

$$d\tau_{(2)}^{yy} = \underbrace{\epsilon^{11}}_{=0} \frac{\partial y}{\partial \theta} \frac{\partial y}{\partial \theta} d\theta d\phi + \epsilon^{12} \frac{\partial y}{\partial \theta} \frac{\partial y}{\partial \phi} d\theta d\phi + \epsilon^{21} \frac{\partial y}{\partial \phi} \frac{\partial y}{\partial \theta} d\theta d\phi + \underbrace{\epsilon^{22}}_{=0} \frac{\partial y}{\partial \phi} \frac{\partial y}{\partial \phi} d\theta d\phi \quad (21)$$

$$= 0 \quad (22)$$

$$d\tau_{(2)}^{zz} = \underbrace{\epsilon^{11}}_{=0} \frac{\partial z}{\partial \theta} \frac{\partial z}{\partial \theta} d\theta d\phi + \epsilon^{12} \frac{\partial z}{\partial \theta} \underbrace{\frac{\partial z}{\partial \phi}}_{=0} d\theta d\phi + \epsilon^{21} \underbrace{\frac{\partial z}{\partial \phi}}_{=0} \frac{\partial z}{\partial \theta} d\theta d\phi + \underbrace{\epsilon^{22}}_{=0} \frac{\partial z}{\partial \phi} \frac{\partial z}{\partial \phi} d\theta d\phi \quad (23)$$

$$= 0 \quad (24)$$

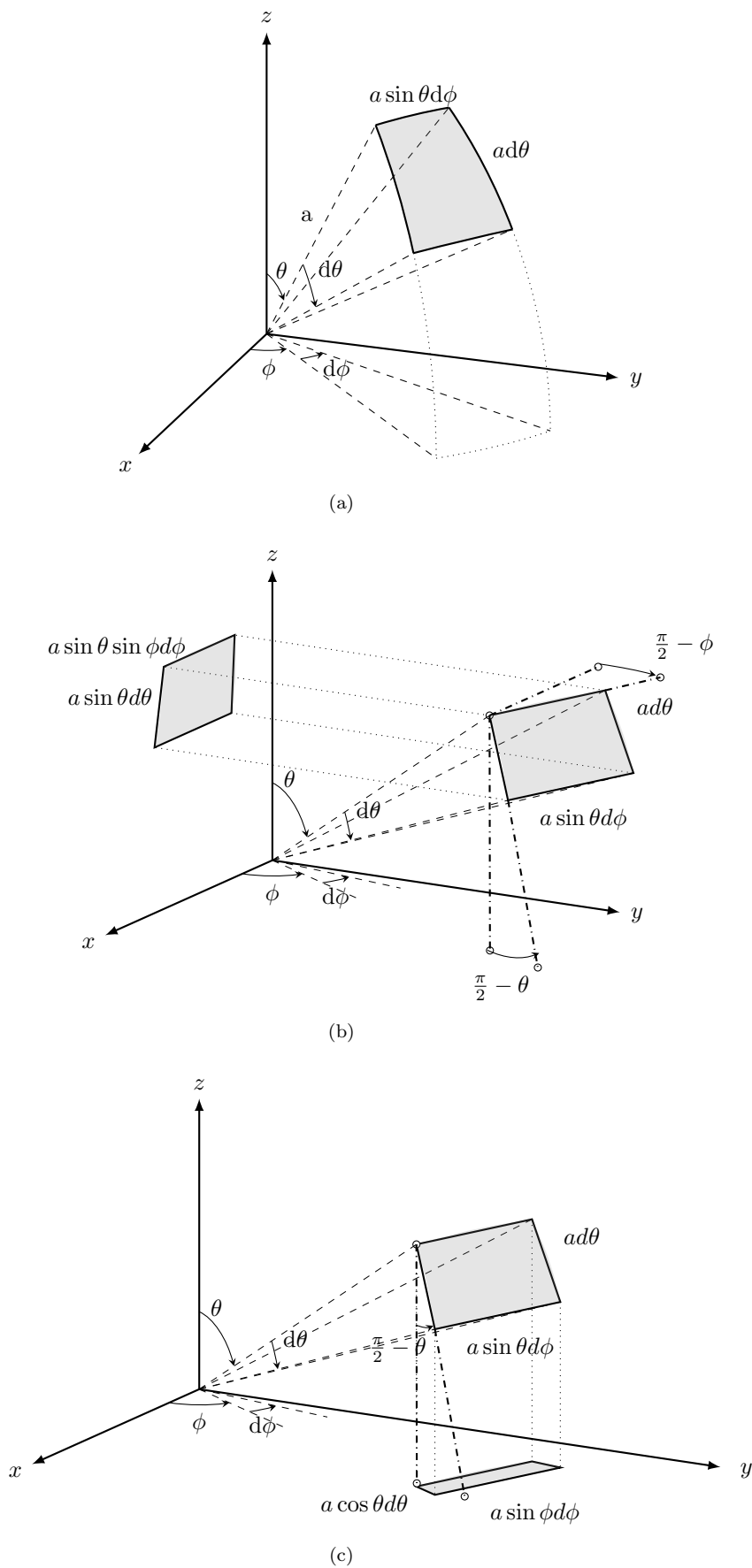


Figure 7.3: Projections of extensions

The quantities $d\tau_{(2)}^{xy}$, $d\tau_{(2)}^{xz}$, $d\tau_{(2)}^{yz}$ are the projections of the extension on the respective Cartesian coordinates planes as can be seen in figure 7.3 where figure (a) depicts the extension (area = $a^2 \sin \theta d\theta d\phi$) when choosing θ, ϕ as the parameters y^k , while figure (b) represents the projection of this extension on the xz -plane and figure (c) represents the projection of this extension on the xy -plane.

◇

Does this interpretation remain valid if the sphere is replaced by some other surface?

The answer is no. For a two-space in Cartesian coordinates system and with surface with parameters (u, v) , equation (2) reduces to

$$d\tau_{(2)}^{xy} = \left(\frac{\partial x}{\partial u} \frac{\partial y}{\partial v} - \frac{\partial x}{\partial v} \frac{\partial y}{\partial u} \right) du dv \quad (25)$$

So $d\tau_{(2)}^{xy} = 0$ if $\frac{\partial x}{\partial u} \frac{\partial y}{\partial v} - \frac{\partial x}{\partial v} \frac{\partial y}{\partial u} = 0$. Consider the disk defined by the following parametric function

$$S : \left\{ \mathbb{R}^2 \rightarrow \mathbb{R}^3 : S(u, v) = \left(\frac{u}{\sqrt{u^2 + v^2 + C}}, \frac{v}{\sqrt{u^2 + v^2 + C}}, 1 \right) \right\}$$

(the constant C is there just to avoid the undefinedness of the surface for $(u, v) = (0, 0)$).

It is easy to see that $\frac{\partial x}{\partial u} \frac{\partial y}{\partial v} - \frac{\partial x}{\partial v} \frac{\partial y}{\partial u} = 0$, yet the surface is parallel with the xy -plane, which implies that the projection on the xy -plane of an elementary cell on S will not have a zero area as can be seen in the figure hereunder.

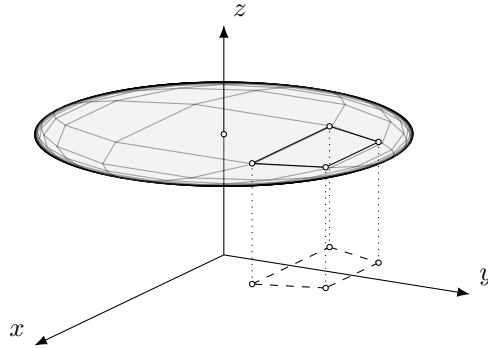


Figure 7.4: A disk defined as $S : \left\{ \mathbb{R}^2 \rightarrow \mathbb{R}^3 : S(u, v) = \left(\frac{u}{\sqrt{u^2 + v^2 + C}}, \frac{v}{\sqrt{u^2 + v^2 + C}}, 1 \right) \right\}$

Conclusion: The interpretation of $d\tau_{(2)}^{k_1 k_2}$ as the projection of a cell on a axis-plane, does not hold for every surface.

◆

7.15 p263 - Exercise

Using polar coordinates in Euclidean 3-space find the volume of an infinitesimal cell whose edges are tangent to the coordinate curves. Obtain the volume of a sphere by integration.

For polar spherical coordinates we have

$$(a_{mn}) = \begin{pmatrix} 1 & 0 & 0 \\ 0 & r^2 & 0 \\ 0 & 0 & r^2 \sin^2 \theta \end{pmatrix} \quad (1)$$

giving

$$|a_{mn}| = r^4 \sin^2 \theta \quad (2)$$

and using as parameters the $x^k \equiv (r, \theta, \phi)$ as parameters for the parametric surface we get

$$|d_{(s)}x^k| = \begin{vmatrix} dr & 0 & 0 \\ 0 & d\theta & 0 \\ 0 & 0 & d\phi \end{vmatrix} \quad (3)$$

$$= dr d\theta d\phi \quad (4)$$

Using **7.405**:

$$dv_{(N)}^2 = \epsilon(a) |a_{mn}| |d_{(s)}x^k|^2 \quad (5)$$

$$= r^4 \sin^2 \theta (dr d\theta d\phi)^2 \quad (6)$$

getting for the volume of a sphere with radius R :

$$V = 8 \int_0^R \int_0^{\frac{\pi}{2}} \int_0^{\frac{\pi}{2}} dv_{(N)} \quad (7)$$

$$= 8 \int_0^R \int_0^{\frac{\pi}{2}} \int_0^{\frac{\pi}{2}} r^2 \sin \theta dr d\theta d\phi \quad (8)$$

$$= \frac{4}{3} \pi R^3 \quad (9)$$



7.16 p265 - Exercise

In the relativistic theory of finite, expanding universe, the following line element is adopted:

$$ds^2 = R^2 [dr^2 + \sin^2 r (d\theta^2 + \sin^2 \theta d\phi^2)] - dt^2$$

where $R = R(t)$ is a function of the "time" t . the ranges of the coordinates may be taken to be $0 \leq r \leq \pi$, $0 \leq \theta \leq \pi$, $0 \leq \phi < 2\pi$, $-\infty < t < +\infty$.

Find the total volume of "space", i.e., of the surface $t = \text{constant}$, and show that it varies with the "time" t as $R^3(t)$.

For the considered metric, we have

$$(a_{mn}) = \begin{pmatrix} R^2 & 0 & 0 & 0 \\ 0 & R^2 \sin^2 r & 0 & 0 \\ 0 & 0 & R^2 \sin^2 r \sin^2 \theta & 0 \\ 0 & 0 & 0 & -1 \end{pmatrix} \quad (1)$$

Using as parameters the $x^k \equiv (r, \theta, \phi)$ as parameters for the parametric surface and using **7.409** : $b_{\alpha\beta} = a_{ks} \frac{\partial x^k}{\partial y^\alpha} \frac{\partial x^s}{\partial y^\beta}$, we get for the 3-space $t = \text{constant}$

$$(b_{mn}) = \begin{pmatrix} R^2 & 0 & 0 \\ 0 & R^2 \sin^2 r & 0 \\ 0 & 0 & R^2 \sin^2 r \sin^2 \theta \end{pmatrix} \quad (2)$$

giving

$$|b_{mn}| = R^6 \sin^4 r \sin^2 \theta \quad (3)$$

Using **7.413**:

$$dv_{(M)}^2 = \frac{\epsilon(b)}{M!} a_{k_1 s_1} \dots a_{k_M s_M} d\tau_{(M)}^{k_1 \dots k_M} d\tau_{(M)}^{s_1 \dots s_M} \quad (4)$$

$$= -\frac{1}{6} a_{k_1 s_1} \dots a_{k_M s_M} d\tau_{(M)}^{k_1 \dots k_M} d\tau_{(M)}^{s_1 \dots s_M} \quad (5)$$

$$= -\frac{6}{6} a_{11} a_{22} a_{33} \left(\underbrace{d\tau_{(M)}^{123}}_{=drd\theta d\phi} \right)^2 \quad (6)$$

$$= -R^6 \sin^4 r \sin^2 \theta (drd\theta d\phi)^2 \quad (7)$$

$$\Rightarrow dv_{(M)} = R^3 \sin^2 r \sin \theta drd\theta d\phi \quad (8)$$

getting for the volume of "space" with "radius" R :

$$V = \int_0^\pi \int_0^\pi \int_0^{2\pi} R^3 \sin^2 r \sin \theta dr d\theta d\phi \quad (9)$$

$$= 2R^3 \pi \int_0^R \sin^2 r dr \underbrace{\int_0^\pi \sin \theta d\theta}_{=-\cos \theta|_0^\pi} \quad (10)$$

$$= 4R^3 \pi \underbrace{\int_0^R \sin^2 r dr}_{=\frac{1}{2}(\theta - \frac{1}{2}\sin(2r))|_0^\pi} \quad (11)$$

$$= 2\pi^2 R^3 \quad (12)$$

(the integral in (11) can be found by substituting $\sin^2 r = 1 - \cos^2 r$ and using the cosine sum of angles rule $\cos(\alpha + \beta) = \cos \alpha \cos \beta - \sin \alpha \sin \beta$ with $\alpha = \beta = r$).

◇

In order to try to understand a little bit better what manifold is represented by the metric, let's use the trick to embed it in an higher dimensional space with an Euclidean metric.

Therefore let's use the following map:

$$\begin{cases} x = R \sin r \sin \theta \cos \phi \\ y = R \sin r \sin \theta \sin \phi \\ z = R \sin r \cos \theta \\ w = R \cos r \end{cases} \quad (13)$$

then it's easy to see that

$$ds_{(4)}^2 = dx^2 + dy^2 + dz^2 + dw^2 \quad (14)$$

$$= R^2 [dr^2 + \sin^2 r (d\theta^2 + \sin^2 \theta d\phi^2)] \quad (15)$$

which is exactly the hypersurface we sought. Now let's see what happens when we keep $\phi = 0$ or π . Then $y = 0$ and in fact we take a slice of the 4-space along the xzw subspace, and can visualize this 3-space as a sphere as represented by figure 7.5(a).

We can also keep r at a certain value. We get also a sphere as represented in figure 7.5(b). Here the biggest possible sphere corresponds to $r = (2k+1)\frac{\pi}{2}$, $k = \{\dots, -1, 0, 1, \dots\}$ all other spheres having a smaller radius. When r tends to $r = k\pi$ $k = \{\dots, -1, 0, 1, \dots\}$ the sphere shrinks to a point with coordinates $(0, 0, 0, \pm R)$.

Finally, keeping $\theta = k\pi$, $k = \{\dots, -1, 0, 1, \dots\}$ we get a circle of radius R situated in the xw plane.

Remember that what we do here is just take 'slices' of a space. compare it to an Euclidean 3-space with a sphere: taking a slice e.g. parallel to the xy plane will give us a circle, a point or an empty set while taking a one-dimensional slice along a line will give us 2, 1 or 0 point(s).

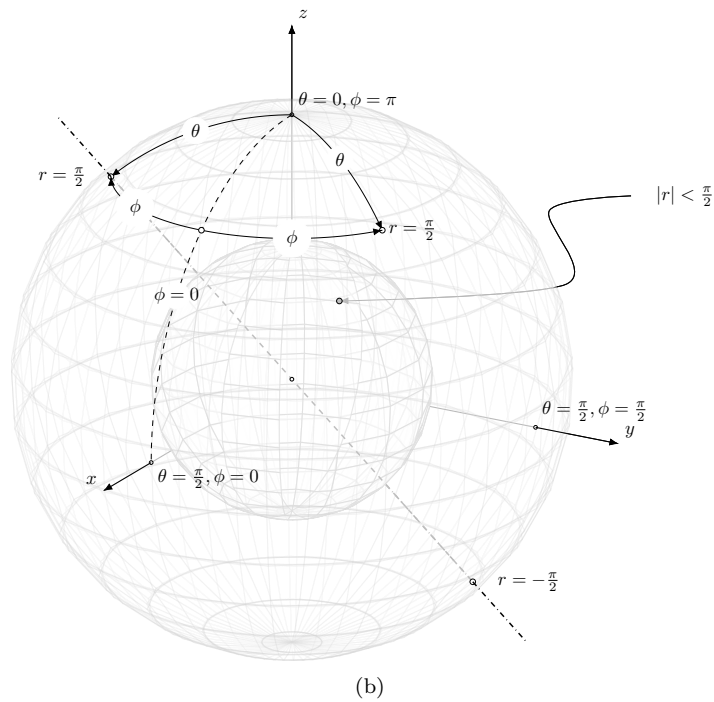
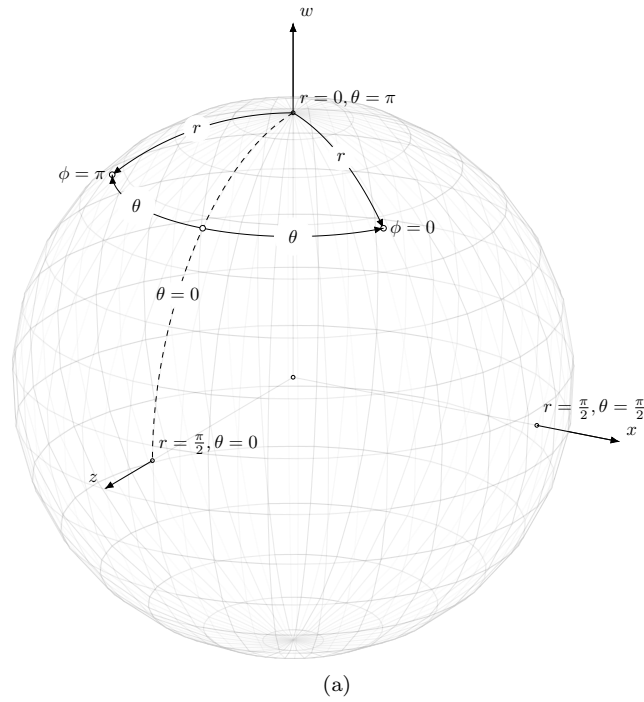


Figure 7.5: Manifold with $ds^2 = R^2 [dr^2 + \sin^2 r (d\theta^2 + \sin^2 \theta d\phi^2)]$ metric, embedded in an Euclidean 4-space



7.17 p268 - Clarification

Since $\frac{\partial T_k}{\partial x^s}$ differs from the tensor $\frac{1}{2} (T_{k,s} - T_{s,k})$ by an expression symmetric in k, s and $d\tau_{(2)}^{ks}$ is an absolute tensor, skew-symmetric in these suffixes, it follows that the integrand on the left is an invariant.

Let's express **7.504** in curvilinear coordinates, equipped with metric

$$\int_{R_2} T_{k|s} d\tau_{(2)}^{ks} = \int_{R_1} T_r d\tau_{(1)}^r \quad (1)$$

Obviously we have

$$T_{k|s} = \frac{1}{2} (T_{k|s} - T_{s|k}) + \frac{1}{2} (T_{k|s} + T_{s|k}) \quad (2)$$

Let's put $A_{ks} = \frac{1}{2} (T_{k|s} - T_{s|k})$ and $B_{ks} = \frac{1}{2} (T_{k|s} + T_{s|k})$.

A_{ks} is skew-symmetric, while B_{ks} is symmetric. Note also that A_{ks} reduces to $A_{ks} = \frac{1}{2} (T_{k,s} - T_{s,k})$ as the Christoffel symbols vanish in this expression, leaving only the partial differentials and hence, independent of a metric. So the integrand on the left side becomes

$$T_{k|s} d\tau_{(2)}^{ks} = A_{ks} d\tau_{(2)}^{ks} + B_{ks} d\tau_{(2)}^{ks} \quad (3)$$

$$\Rightarrow T_{k|s} d\tau_{(2)}^{ks} = A_{ks} d\tau_{(2)}^{ks} - B_{ks} d\tau_{(2)}^{sk} \quad (4)$$

$$= A_{ks} d\tau_{(2)}^{ks} - B_{sk} d\tau_{(2)}^{sk} \quad (5)$$

$$(3)+(5) \Rightarrow T_{k|s} d\tau_{(2)}^{ks} = A_{ks} d\tau_{(2)}^{ks} \quad (6)$$

We note that both A_{ks} and $d\tau_{(2)}^{ks}$ are tensors, independent of the metric defined, and thus $A_{ks} d\tau_{(2)}^{ks}$ is an invariant of order 0.



7.18 p274 - Exercise

Due to the skew-symmetry of $d\tau_{(M)}^{k_1 \dots k_M}$, the integrand on the left-hand side is also an invariant. This may be proved in a few lines, preferably with the use of the compressed notation of 1.7; the proof is left as an exercise for the reader.

We will use the indices i, j for the transformed tensor components and p, q for the original components. We have

$$T'_{i_1 \dots i_{M-1}} = T_{p_1 \dots p_{M-1}} X_{i_1}^{p_1} \dots X_{i_{M-1}}^{p_{M-1}} \quad (1)$$

$$\Rightarrow T'_{i_1 \dots i_{M-1}, i_M} = T_{p_1 \dots p_{M-1}, i_M} X_{i_1}^{p_1} \dots X_{i_{M-1}}^{p_{M-1}} + T_{p_1 \dots p_{M-1}} \left(X_{i_1}^{p_1} \dots X_{i_{M-1}}^{p_{M-1}} \right)_{, i_M} \quad (2)$$

$$= T_{p_1 \dots p_{M-1}, p_M} X_{i_1}^{p_1} \dots X_{i_{M-1}}^{p_{M-1}} X_{i_M}^{p_M} + T_{p_1 \dots p_{M-1}} \left(X_{i_1}^{p_1} \dots X_{i_{M-1}}^{p_{M-1}} \right)_{, i_M} \quad (3)$$

and

$$d\tau'_{(M)} = d\tau_{(M)}^{s_1 \dots s_M} X_{s_1}^{i_1} \dots X_{s_M}^{i_M} \quad (4)$$

This gives

$$T'_{i_1 \dots i_{M-1}, i_M} d\tau'_{(M)} = \begin{cases} T_{p_1 \dots p_{M-1}, p_M} X_{i_1}^{p_1} \dots X_{i_{M-1}}^{p_{M-1}} X_{i_M}^{p_M} d\tau_{(M)}^{s_1 \dots s_M} X_{s_1}^{i_1} \dots X_{s_M}^{i_M} \\ + T_{p_1 \dots p_{M-1}} \left(X_{i_1}^{p_1} \dots X_{i_{M-1}}^{p_{M-1}} \right)_{, i_M} d\tau_{(M)}^{s_1 \dots s_M} X_{s_1}^{i_1} \dots X_{s_M}^{i_M} \end{cases} \quad (5)$$

$$= T_{p_1 \dots p_{M-1}, p_M} X_{s_1}^{p_1} \dots X_{s_{M-1}}^{p_{M-1}} X_{s_M}^{p_M} d\tau_{(M)}^{s_1 \dots s_M} \quad (6)$$

$$= T_{p_1 \dots p_{M-1}, p_M} \delta_{s_1}^{p_1} \dots \delta_{s_{M-1}}^{p_{M-1}} \delta_{s_M}^{p_M} d\tau_{(M)}^{s_1 \dots s_M} \quad (7)$$

$$= T_{s_1 \dots s_{M-1}, s_M} d\tau_{(M)}^{s_1 \dots s_M} \quad (8)$$

The term $T_{p_1 \dots p_{M-1}} \left(X_{i_1}^{p_1} \dots X_{i_{M-1}}^{p_{M-1}} \right)_{, i_M} d\tau_{(M)}^{s_1 \dots s_M} X_{s_1}^{i_1} \dots X_{s_M}^{i_M}$ in (5) is zero. Indeed, rewriting this as :

$$T_{p_1 \dots p_{M-1}} \left(X_{i_1}^{p_1} \dots X_{i_{M-1}}^{p_{M-1}} \right)_{, p_M} X_{i_M}^{p_M} d\tau_{(M)}^{s_1 \dots s_M} X_{s_1}^{i_1} \dots X_{s_M}^{i_M} \quad (9)$$

The terms in brackets are zero as they are of the form

$$\dots + X_{i_1}^{p_1} \dots \underbrace{\frac{\partial^2 x^{p_m}}{\partial x^{p_M} \partial x^{i_m}}}_{= \frac{\partial \delta_{p_M}^{p_m}}{\partial x^{i_m}} = 0} \dots X_{i_{M-1}}^{p_{M-1}} + \dots \quad (10)$$

From (8) we conclude that the integrand is indeed an invariant.



7.19 p275 - Exercise

The skew-symmetric part of a tensor $T_{k_1 \dots k_M}$ is defined as

$$T_{[k_1 \dots k_M]} = (M!)^{-1} \delta_{k_1 \dots k_M}^{s_1 \dots s_M} T_{s_1 \dots s_M}$$

Show that the left-hand side of equation **7.525** is unchanged if $T_{k_1 \dots k_M}$ is replaced by its skew-symmetric part. Show that the same is true for the right-hand side.

The integrand of the left-hand side of **7.525** is

$$T_{k_1 \dots k_{M-1}, k_M} d\tau_{(M)}^{k_1 \dots k_M} \quad (1)$$

replacing the tensor with its skew-symmetric part gives

$$T_{[k_1 \dots k_{M-1}], k_M} d\tau_{(M)}^{k_1 \dots k_M} = \frac{1}{(M-1)!} \delta_{k_1 \dots k_{M-1}}^{s_1 \dots s_{M-1}} T_{s_1 \dots s_{M-1}, k_M} d\tau_{(M)}^{k_1 \dots k_M} \quad (2)$$

$$= \frac{1}{(M-1)!} \delta_{k_1 \dots k_{M-1}}^{s_1 \dots s_{M-1}} \delta_{k_M}^{s_M} T_{s_1 \dots s_{M-1}, s_M} d\tau_{(M)}^{k_1 \dots k_M} \quad (3)$$

$$= \frac{1}{(M-1)!} \delta_{k_1 \dots k_{M-1}}^{s_1 \dots s_{M-1}} T_{s_1 \dots s_{M-1}, s_M} d\tau_{(M)}^{k_1 \dots k_{M-1} s_M} \quad (4)$$

$$= T_{s_1 \dots s_{M-1}, s_M} \frac{1}{(M-1)!} \left(\delta_{k_1 \dots k_{M-1}}^{s_1 \dots s_{M-1}} d\tau_{(M)}^{k_1 \dots k_{M-1} s_M} \right) \quad (5)$$

$$(6)$$

The terms in the brackets can be reduced to $(M-1)! d\tau_{(M)}^{s_1 \dots s_{M-1} s_M}$. Indeed, the number of choices in choosing the k_1, \dots, k_{M-1} are restricted to $M-1$ choices, due to the skew-symmetry of $d\tau_{(M)}^{k_1 \dots k_{M-1} s_M}$ (choosing a $k_i = s_M$ would result in a zero value for $d\tau_{(M)}^{k_1 \dots k_{M-1} s_M}$). So, in total there will be $(M-1)!$ terms and due to the skew-symmetry of $d\tau_{(M)}^{k_1 \dots k_{M-1} s_M}$ a change in sign of $\delta_{k_1 \dots k_{M-1}}^{s_1 \dots s_{M-1}}$ will also result in a change of sign in $d\tau_{(M)}^{k_1 \dots k_{M-1} s_M}$. Hence, we get

$$T_{[k_1 \dots k_{M-1}], k_M} d\tau_{(M)}^{k_1 \dots k_M} = T_{s_1 \dots s_{M-1}, s_M} \frac{1}{(M-1)!} (M-1)! d\tau_{(M)}^{s_1 \dots s_{M-1} s_M} \quad (7)$$

$$= T_{s_1 \dots s_{M-1}, s_M} d\tau_{(M)}^{s_1 \dots s_{M-1} s_M} \quad (8)$$

◇

The integrand of the right-hand side of **7.525** is

$$T_{k_1 \dots k_{M-1}} d\tau_{(M-1)}^{k_1 \dots k_{M-1}} \quad (9)$$

replacing the tensor with it's skew-symmetric part gives

$$T_{[k_1 \dots k_{M-1}]} d\tau_{(M-1)}^{k_1 \dots k_{M-1}} = \frac{1}{(M-1)!} \delta_{k_1 \dots k_{M-1}}^{s_1 \dots s_{M-1}} T_{s_1 \dots s_{M-1}} d\tau_{(M-1)}^{k_1 \dots k_{M-1}} \quad (10)$$

$$= T_{s_1 \dots s_{M-1}} \frac{1}{(M-1)!} \left(\delta_{k_1 \dots k_{M-1}}^{s_1 \dots s_{M-1}} d\tau_{(M-1)}^{k_1 \dots k_{M-1}} \right) \quad (11)$$

The terms in the brackets can be reduced to $(M-1)! d\tau_{(M-1)}^{s_1 \dots s_{M-1}}$. Indeed, the number of choices in choosing the k_1, \dots, k_{M-1} is $M-1$, giving $(M-1)!$ terms and due to the skew-symmetry of $d\tau_{(M-1)}^{k_1 \dots k_{M-1}}$ a change in sign of $\delta_{k_1 \dots k_{M-1}}^{s_1 \dots s_{M-1}}$ will also result in a change of sign in $d\tau_{(M-1)}^{k_1 \dots k_{M-1}}$. Hence, we get

$$T_{[k_1 \dots k_{M-1}]} d\tau_{(M-1)}^{k_1 \dots k_{M-1}} = T_{s_1 \dots s_{M-1}} \frac{1}{(M-1)!} (M-1)! d\tau_{(M-1)}^{s_1 \dots s_{M-1}} \quad (12)$$

$$= T_{s_1 \dots s_{M-1}} d\tau_{(M-1)}^{s_1 \dots s_{M-1}} \quad (13)$$



7.20 p278 - Exercise 1

Show from **7.312** that the number of independent components of the extension of an M -cell in N -space is

$$\frac{N!}{M!(N-M)!}$$

$$\mathbf{7.312}: \quad d\tau^{k_1 \dots k_M} = \epsilon^{\alpha_1 \dots \alpha_M} \frac{\partial x^{k_1}}{\partial y^{\alpha_1}} \dots \frac{\partial x^{k_M}}{\partial y^{\alpha_M}} |d_{(\beta)} y^\gamma| \quad (1)$$

As all k_i are different, the unconstrained number of ordered arrangement of M elements picked out of a set of N possibilities is $N(N-1) \dots (N-M+1) = \frac{N!}{(N-M)!}$.

As $d\tau^{k_1 \dots k_M}$ is skew-symmetric we have to divide this number by the number of constraints of the form $d\tau^{k_1 \dots k_j \dots k_p \dots k_M} = -d\tau^{k_1 \dots k_p \dots k_j \dots k_M}$. This number just corresponds to the number of permutations of M distinct objects and is equal to $M!$.

Hence,

$$\frac{N!}{M!(N-M)!}$$



7.21 p278 - Exercise 2

Prove that the covariant derivative of a generalized Kronecker delta is zero.

(2.525) gives:

$$\delta_{s_1 \dots s_M | s_\tau}^{k_1 \dots k_M} = \underbrace{\frac{\partial \delta_{s_1 \dots s_M}^{k_1 \dots k_M}}{\partial x^{s_\tau}}}_{=0} + \Gamma_{qs_\tau}^{k_1} \delta_{s_1 \dots s_M}^{q k_2 \dots k_M} + \dots + \Gamma_{qs_\tau}^{k_M} \delta_{s_1 \dots s_M}^{k_1 \dots k_{(M-1)} q} - \Gamma_{s_1 s_\tau}^q \delta_{q s_2 \dots s_M}^{k_1 \dots k_M} - \dots - \Gamma_{s_M s_\tau}^q \delta_{s_1 \dots s_{(M-1)} q}^{k_1 \dots k_M} \quad (1)$$

(2)

Let us now consider the following notation for $\delta_{s_1 \dots s_M}^{k_1 \dots k_M}$

$$\delta_{s_1 \leftrightarrow k_y \leftrightarrow s_M}^{k_1 \leftrightarrow s_x \leftrightarrow k_M}$$

showing the respective position of an element in the two series use in the generalized Kronecker delta.

Consider in this expression (no summations on the indexes) the positive and negative terms like

$$\Gamma_{qs_\tau}^{k_y} \delta_{s_1 \leftrightarrow k_y \leftrightarrow s_M}^{k_1 \leftrightarrow q \leftrightarrow k_M} \Big|_{q \neq s_x}, \dots, - \Gamma_{s_x s_\tau}^q \delta_{s_1 \leftrightarrow s_x \leftrightarrow s_M}^{k_1 \leftrightarrow q \leftrightarrow k_M} \Big|_{q \neq k_y} \quad (3)$$

Obviously these terms are zero as q does not refer to the value necessary to have no repetition in the set $\{s_1 \dots s_M\}$ or $\{k_1 \dots k_M\}$.

Consider now the sum of two terms like (no summations on the indexes).

$$\Gamma_{qs_\tau}^{k_y} \delta_{s_1 \leftrightarrow k_y \leftrightarrow s_M}^{k_1 \leftrightarrow q \leftrightarrow k_M} \Big|_{q=s_x} - \Gamma_{s_x s_\tau}^q \delta_{s_1 \leftrightarrow s_x \leftrightarrow s_M}^{k_1 \leftrightarrow q \leftrightarrow k_M} \Big|_{q=k_y} \quad (4)$$

(5)

As each term in this sum occurs only once in (1) and we get

$$\Gamma_{qs_\tau}^{k_y} \delta_{s_1 \leftrightarrow k_y \leftrightarrow s_M}^{k_1 \leftrightarrow q \leftrightarrow k_M} \Big|_{q=s_x} - \Gamma_{s_x s_\tau}^q \delta_{s_1 \leftrightarrow s_x \leftrightarrow s_M}^{k_1 \leftrightarrow q \leftrightarrow k_M} \Big|_{q=k_y} \quad (6)$$

$$= \delta_{s_1 \dots s_M}^{k_1 \dots k_M} (\Gamma_{s_x s_\tau}^{k_y} - \Gamma_{s_x s_\tau}^{k_y}) \quad (7)$$

$$= 0 \quad (8)$$

This show that indeed the covariant derivative of the generalize Kronecker delta is zero.

◇

Note: probably this can also be proved by induction, starting with the result in exercise in chapter 2, page 53 (see part I of this solution manual).

◆

7.22 p278 - Exercise 3

Show that

$$\delta_{k_1 \dots k_M}^{s_1 \dots s_M} = \begin{vmatrix} \delta_{s_1}^{k_1} & \delta_{s_2}^{k_1} & \dots & \delta_{s_M}^{k_1} \\ \vdots & \vdots & \vdots & \vdots \\ \delta_{s_1}^{k_M} & \delta_{s_2}^{k_M} & \dots & \delta_{s_M}^{k_M} \end{vmatrix}$$

The determinant on the right side can be represented as

$$\Delta = \epsilon_{i_1 i_2 \dots i_M} \delta_{s_1}^{k_{i_1}} \delta_{s_2}^{k_{i_2}} \dots \delta_{s_M}^{k_{i_M}} \quad (1)$$

Be K_M, S_M the (unordered) sets $\{k_1, k_2, \dots, k_M\}$ and $\{s_1, s_2, \dots, s_M\}$. If $K_M \neq S_M$ then, one of the elements will differ and from (1) it follows that $\Delta = 0$ as for all terms in (1) at least one of the $\delta_{s_m}^{k_{i_n}}$ will be zero.

If $K_M = S_M$ then there will be only 1 term left in (1) having value ± 1 depending on the value of the corresponding $\epsilon_{i_1 i_2 \dots i_M}$ associated with this term. Be \hat{K}_M, \hat{S}_M the (ordered) list generated by K_M, S_M , then the value of the $\epsilon_{i_1 i_2 \dots i_M}$ will be determined by the number of permutation needed to map bijectively \hat{K}_M to \hat{S}_M . The above reasoning shows that the determinant can be expressed as

$$\Delta = \delta_{k_1 \dots k_M}^{s_1 \dots s_M}$$



7.23 p278 - Exercise 4

If T_{rs} is a symmetric tensor density and S_{rs} a skew-symmetric tensor density, show that

$$\begin{aligned} T_{.s|r}^r &= \partial_r T_{.s}^r - \frac{1}{2} T^{rk} \partial_s a_{rk} \\ S_{..|r}^{rs} &= \partial_r S^{rs} \end{aligned}$$

Let's define the absolute oriented tensor.

$$\bar{T}_{.s}^r = (\epsilon(a)a)^{-\frac{1}{2}} T_{.s}^r \quad (1)$$

By **7.214** we have

$$T_{.s|r}^r = (\epsilon(a)a)^{\frac{1}{2}} \left[\bar{T}_{.s}^r \right]_{|r} \quad (2)$$

with

$$\left[\bar{T}_{.s}^r \right]_{|r} = \partial_r \bar{T}_{.s}^r + \Gamma_{mr}^r \bar{T}_{.s}^m - \Gamma_{rs}^m \bar{T}_{.m}^r \quad (3)$$

Using **2.542** : $\Gamma_{mr}^r = (\epsilon(a)a)^{-\frac{1}{2}} \partial_m (\epsilon(a)a)^{\frac{1}{2}}$

$$\left[\bar{T}_{.s}^r \right]_{|r} = \begin{cases} (\epsilon(a)a)^{-\frac{1}{2}} \partial_r T_{.s}^r + T_{.s}^r \partial_r (\epsilon(a)a)^{-\frac{1}{2}} \\ + (\epsilon(a)a)^{-\frac{1}{2}} \partial_m (\epsilon(a)a)^{\frac{1}{2}} \bar{T}_{.s}^m \\ - \frac{1}{2} (\partial_s a_{rk} + \partial_r a_{sk} - \partial_k a_{rs}) a^{mk} \bar{T}_{.m}^r \end{cases} \quad (4)$$

$$= \begin{cases} (\epsilon(a)a)^{-\frac{1}{2}} \partial_r T_{.s}^r + T_{.s}^r \partial_r (\epsilon(a)a)^{-\frac{1}{2}} \\ + (\epsilon(a)a)^{-\frac{1}{2}} (\epsilon(a)a)^{-\frac{1}{2}} T_{.s}^m \partial_m (\epsilon(a)a)^{\frac{1}{2}} \\ - \frac{1}{2} (\epsilon(a)a)^{-\frac{1}{2}} \left(T^{rk} \partial_s a_{rk} + \underbrace{T^{rk} \partial_r a_{sk} - T^{rk} \partial_k a_{rs}}_{=0} \right) \end{cases} \quad (5)$$

$$= \begin{cases} (\epsilon(a)a)^{-\frac{1}{2}} \left(\partial_r T_{.s}^r - \frac{1}{2} T^{rk} \partial_s a_{rk} \right) \\ + T_{.s}^r \left[\partial_r (\epsilon(a)a)^{-\frac{1}{2}} + (\epsilon(a)a)^{-1} \partial_r (\epsilon(a)a)^{\frac{1}{2}} \right] \end{cases} \quad (6)$$

$$= \begin{cases} (\epsilon(a)a)^{-\frac{1}{2}} \left(\partial_r T_{.s}^r - \frac{1}{2} T^{rk} \partial_s a_{rk} \right) \\ + T_{.s}^r \left[\underbrace{-\frac{1}{2} (\epsilon(a))^{-\frac{3}{2}} \partial_r (\epsilon(a)a) + \frac{1}{2} (\epsilon(a)a)^{-1} (\epsilon(a)a)^{-\frac{1}{2}} \partial_r (\epsilon(a)a)}_{=0} \right] \end{cases} \quad (7)$$

giving

$$\left[\overline{T}^r_{.s} \right]_{|r} = (\epsilon(a)a)^{-\frac{1}{2}} \left(\partial_r T^r_{.s} - \frac{1}{2} T^{rk} \partial_s a_{rk} \right) \quad (8)$$

$$(2) \text{ and } (8): \quad T^r_{.s|r} = \partial_r T^r_{.s} - \frac{1}{2} T^{rk} \partial_s a_{rk} \quad (9)$$

◇

Let's define the absolute oriented tensor.

$$\overline{S}^{rs} = (\epsilon(a)a)^{-\frac{1}{2}} S^{rs} \quad (10)$$

By **7.214** we have

$$S^{rs}_{.|r} = (\epsilon(a)a)^{\frac{1}{2}} \left[\overline{S}^{rs} \right]_{|r} \quad (11)$$

with

$$\left[\overline{S}^{rs} \right]_{|r} = \partial_r \overline{S}^{rs} + \Gamma^r_{mr} \overline{S}^{ms} + \Gamma^s_{mr} \overline{S}^{rm} \quad (12)$$

$$\text{Using } \mathbf{2.542} : \quad \Gamma^r_{mr} = (\epsilon(a)a)^{-\frac{1}{2}} \partial_m (\epsilon(a)a)^{\frac{1}{2}}$$

$$\left[\overline{S}^{rs} \right]_{|r} = \begin{cases} (\epsilon(a)a)^{-\frac{1}{2}} \partial_r S^{rs} + S^{rs} \partial_r (\epsilon(a)a)^{-\frac{1}{2}} \\ + (\epsilon(a)a)^{-\frac{1}{2}} \partial_m (\epsilon(a)a)^{\frac{1}{2}} \overline{S}^{ms} \\ + \frac{1}{2} (\partial_m a_{rk} + \partial_r a_{mk} - \partial_k a_{mr}) a^{sk} \overline{S}^{rm} \end{cases} \quad (13)$$

$$= \begin{cases} (\epsilon(a)a)^{-\frac{1}{2}} \partial_r S^{rs} + S^{rs} \partial_r (\epsilon(a)a)^{-\frac{1}{2}} \\ + (\epsilon(a)a)^{-\frac{1}{2}} (\epsilon(a)a)^{-\frac{1}{2}} S^{ms} \partial_m (\epsilon(a)a)^{\frac{1}{2}} \\ + \frac{1}{2} (\epsilon(a)a)^{-\frac{1}{2}} (S^{rm} \partial_m a_{rk} + S^{rm} \partial_r a_{mk} - S^{rm} \partial_k a_{mr}) a^{sk} \end{cases} \quad (14)$$

$$(15)$$

Using the skew-symmetry of S_{rm} we get

$$\left[\bar{S}^{rs} \right]_{|r} = \begin{cases} (\epsilon(a)a)^{-\frac{1}{2}} \partial_r S^{rs} \\ \underbrace{S^{rs} \partial_r (\epsilon(a)a)^{-\frac{1}{2}} + (\epsilon(a)a)^{-1} S^{ms} \partial_m (\epsilon(a)a)^{\frac{1}{2}}}_{=0} \\ + \frac{1}{2} (\epsilon(a)a)^{-\frac{1}{2}} \left(\underbrace{S^{rm} \partial_m a_{rk} + S^{rm} \partial_r a_{mk} - S^{rm} \partial_k a_{mr}}_{=0} \right) a^{sk} \end{cases} \quad (16)$$

$$= \begin{cases} (\epsilon(a)a)^{-\frac{1}{2}} \partial_r S^{rs} \\ -\frac{1}{2} (\epsilon(a)a)^{-\frac{1}{2}} (a^{sk} \partial_k a_{mr} S^{rm}) \end{cases} \quad (17)$$

$$(18)$$

In the last term, put $b_{smr} \doteq a^{sk} \partial_k a_{mr}$ which is symmetric in the last two indexes. Due to the skew-symmetry of S^{rm} we have then $b_{srm} S^{rm} = 0$ and get

$$\left[\bar{S}^{rs} \right]_{|r} = (\epsilon(a)a)^{-\frac{1}{2}} \partial_r S^{rs} \quad (19)$$

$$(2) \text{ and } (19): \quad S_{\cdot\cdot|r}^{rs} = \partial_r S^{rs} \quad (20)$$



7.24 p279 - Exercise 5

Let b_{mn} an absolute covariant tensor. Show that the cofactors of the elements b_{mn} in the determinant $|b_{mn}|$ are the components of a relative contravariant tensor of weight 2.

Let's put $b \doteq |b_{mn}|$. We have (see **2.202**)

$$b_{mr}\Delta^{ms} = \delta_r^s b \quad (1)$$

where Δ^{ms} is the cofactor associated with element b_{ms} . Note that, for the moment being, the position of the indexes does not imply any tensor characteristics of this object. δ_r^s is a mixed absolute tensor of order 2 (see page 243). Also b is a relative invariant of weight 2 (see **7.202**).

So we have the following transformation rules

$$\left\{ \begin{array}{l} \delta_r'^s = \delta_v^u \frac{\partial x'^s}{\partial x^u} \frac{\partial x^v}{\partial x'^r} \\ b' = J^2 b \\ b'_{mr} = b_{uv} \frac{\partial x^u}{\partial x'^m} \frac{\partial x^v}{\partial x'^r} \end{array} \right. \quad (2)$$

Using (1)

$$b'_{mr}\Delta'^{ms} = \delta_r'^s b' \quad (3)$$

Substituting with (2)

$$b_{uv} \frac{\partial x^u}{\partial x'^m} \frac{\partial x^v}{\partial x'^r} \Delta'^{ms} = \delta_v^u \frac{\partial x'^s}{\partial x^u} \frac{\partial x^v}{\partial x'^r} J^2 b \quad (4)$$

$$b_{uv} \frac{\partial x^u}{\partial x'^m} \frac{\partial x^v}{\partial x'^r} \Delta'^{ms} = \frac{\partial x'^s}{\partial x^u} \frac{\partial x^v}{\partial x'^r} J^2 b_{mv} \Delta^{mu} \quad (5)$$

$$\times \frac{\partial x'^r}{\partial x^p} \quad b_{up} \frac{\partial x^u}{\partial x'^m} \Delta'^{ms} = J^2 b_{mp} \Delta^{mu} \frac{\partial x'^s}{\partial x^u} \quad (6)$$

This is a system of N^2 linear equations in N^2 unknowns Δ'^{ms} . We claim that $\Delta'^{ms} = J^2 \Delta^{ij} \frac{\partial x'^m}{\partial x^i} \frac{\partial x'^s}{\partial x^j}$ is a solution of that system.

Substituting this candidate solution in the left side of (6) gives

$$b_{up} \frac{\partial x^u}{\partial x'^m} J^2 \Delta^{ij} \frac{\partial x'^m}{\partial x^i} \frac{\partial x'^s}{\partial x^j} = J^2 b_{up} \delta_i^u \Delta^{ij} \frac{\partial x'^s}{\partial x^j} \quad (7)$$

$$= J^2 b_{mp} \Delta^{mu} \frac{\partial x'^s}{\partial x^u} \quad (8)$$

proving that our candidate solution is indeed the solution for (6), provided of course the usual conditions on the solvability of a system of linear equations.



7.25 p279 - Exercise 6

Determine the tensor character of the cofactors in the determinants formed by the components of

- (a) a mixed absolute tensor
- (b) a relative contravariant tensor of weight 1.

(a)

Let's put $b \doteq |b_n^m|$. We have (see **2.202**)

$$b_r^m \Delta^{ms} = \delta_r^s b \quad (1)$$

where Δ^{ms} is the cofactor associated with element b_s^m . Note that, for the moment being, the position of the indexes does not imply any tensor characteristics of this object. δ_r^s is a mixed absolute tensor of order 2 (see page 243). Also b is a relative invariant of weight 2 (see **7.202**).

So we have the following transformation rules

$$\left\{ \begin{array}{l} \delta_r'^s = \delta_v^u \frac{\partial x'^s}{\partial x^u} \frac{\partial x^v}{\partial x'^r} \\ b' = J^2 b \\ b_r'^m = b_v^u \frac{\partial x'^m}{\partial x^u} \frac{\partial x^v}{\partial x'^r} \end{array} \right. \quad (2)$$

Using (1)

$$b_r'^m \Delta'^{ms} = \delta_r'^s b' \quad (3)$$

Substituting with (2)

$$b_v^u \frac{\partial x'^m}{\partial x^u} \frac{\partial x^v}{\partial x'^r} \Delta'^{ms} = \delta_v^u \frac{\partial x'^s}{\partial x^u} \frac{\partial x^v}{\partial x'^r} J^2 b \quad (4)$$

$$b_v^u \frac{\partial x'^m}{\partial x^u} \frac{\partial x^v}{\partial x'^r} \Delta'^{ms} = \frac{\partial x'^s}{\partial x^u} \frac{\partial x^v}{\partial x'^r} J^2 b_v^m \Delta^{mu} \quad (5)$$

$$\times \frac{\partial x'^r}{\partial x^p} \quad b_p^u \frac{\partial x'^m}{\partial x^u} \Delta'^{ms} = J^2 b_p^m \Delta^{mu} \frac{\partial x'^s}{\partial x^u} \quad (6)$$

This is a system of N^2 linear equations in N^2 unknowns Δ'^{ms} . We claim that $\Delta'^{ms} = J^2 \Delta^{ij} \frac{\partial x^i}{\partial x'^m} \frac{\partial x'^s}{\partial x^j}$ is a solution of that system.

Substituting this candidate solution in the left side of (6) gives

$$b_p^u \frac{\partial x'^m}{\partial x^u} J^2 \Delta^{ij} \frac{\partial x^i}{\partial x'^m} \frac{\partial x'^s}{\partial x^j} = J^2 b_p^u \delta_u^i \Delta^{ij} \frac{\partial x'^s}{\partial x^j} \quad (7)$$

$$= J^2 b_p^m \Delta^{mu} \frac{\partial x'^s}{\partial x^u} \quad (8)$$

proving that our candidate solution is indeed the solution for (6), provided of course the usual conditions on the solvability of a system of linear equations.

We rewrite the cofactor as Δ_m^s which transform as

$$\Delta_m^s = J^2 \Delta_j^i \frac{\partial x^i}{\partial x'^m} \frac{\partial x'^s}{\partial x^j}$$

and conclude that the cofactor is a relative mixed tensor of weight 2.

◇

(b) Let's put $b \doteq |b^{mn}|$. We have (see **2.202**)

$$b^{mr} \Delta^{ms} = \delta_r^s b \quad (9)$$

where Δ^{ms} is the cofactor associated with element b^{ms} . Note that, for the moment being, the position of the indexes does not imply any tensor characteristics of this object. δ_r^s is a mixed absolute tensor of order 2 (see page 243). Also b is a relative invariant of weight 2 (see **7.202**).

So we have the following transformation rules

$$\left\{ \begin{array}{l} \delta_r'^s = \delta_v^u \frac{\partial x'^s}{\partial x^u} \frac{\partial x^v}{\partial x'^r} \\ b' = J^2 b \\ b'^{mr} = J b^{uv} \frac{\partial x'^m}{\partial x^u} \frac{\partial x'^r}{\partial x^v} \end{array} \right. \quad (10)$$

Using (1)

$$b'^{mr} \Delta'^{ms} = \delta_r'^s b' \quad (11)$$

Substituting with (2)

$$J b^{uv} \frac{\partial x'^m}{\partial x^u} \frac{\partial x'^r}{\partial x^v} \Delta'^{ms} = \delta_v^u \frac{\partial x'^s}{\partial x^u} \frac{\partial x^v}{\partial x'^r} J^2 b \quad (12)$$

$$J b^{uv} \frac{\partial x'^m}{\partial x^u} \frac{\partial x'^r}{\partial x^v} \Delta'^{ms} = \frac{\partial x'^s}{\partial x^u} \frac{\partial x^v}{\partial x'^r} J^2 b^{mv} \Delta^{mu} \quad (13)$$

$$\times \frac{\partial x^p}{\partial x'^r} \quad b^{up} \frac{\partial x'^m}{\partial x^u} \Delta'^{ms} = J b^{mp} \Delta^{mu} \frac{\partial x'^s}{\partial x^u} \quad (14)$$

This is a system of N^2 linear equations in N^2 unknowns Δ'^{ms} . We claim that $\Delta'^{ms} = J \Delta^{ij} \frac{\partial x^i}{\partial x'^m} \frac{\partial x'^s}{\partial x^j}$ is a solution of that system.

Substituting this candidate solution in the left side of (6) gives

$$b^{up} \frac{\partial x'^m}{\partial x^u} J \Delta^{ij} \frac{\partial x^i}{\partial x'^m} \frac{\partial x'^s}{\partial x^j} = J b^{up} \delta_u^i \Delta^{ij} \frac{\partial x'^s}{\partial x^j} \quad (15)$$

$$= J b^{mp} \Delta^{mu} \frac{\partial x'^s}{\partial x^u} \quad (16)$$

proving that our candidate solution is indeed the solution for (6), provided of course the usual conditions on the solvability of a system of linear equations.

We rewrite the cofactor as Δ_m^s which transform as

$$\Delta_m^s = J \Delta_j^i \frac{\partial x^i}{\partial x'^m} \frac{\partial x'^s}{\partial x^j}$$

and conclude that the cofactor is a relative mixed tensor of weight 1.



7.26 p279 - Exercise 7

In the space-time of relativity with metric form

$$(dx^1)^2 + (dx^2)^2 + (dx^3)^2 - (dx^4)^2$$

the 3-space with equation

$$(x^1)^2 + (x^2)^2 + (x^3)^2 - (x^4)^2 = 0$$

is called a null cone. prove that the 3-volume of any portion of the null cone is zero.

We have **7.414** : $v_{(3)} = \int_{R(3)} dv_{(3)}$ with **7.410** : $dv_{(3)} = (\epsilon(b)b)^{\frac{1}{2}} \epsilon(\tau) |d_{(\beta)} y_{\alpha}|$ and **(7.409)** : $b_{\alpha\beta} = a_{ks} \frac{\partial x^k}{\partial y_{\alpha}} \frac{\partial x^s}{\partial y_{\beta}}$. Let's compute $b = |b_{\alpha\beta}|$. We define the intrinsic parameters (x^1, x^2, x^3) for the (y_{α}) . We have

$$(a_{mn}) = \begin{vmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & -1 \end{vmatrix} \quad (1)$$

Let's define $R = \sqrt{(y^1)^2 + (y^2)^2 + (y^3)^2}$ and using the equation of the null cone in the form

$$(x^4)^2 = R^2$$

we get

$$|b_{mn}| = \begin{vmatrix} 1 - \left(\frac{x^1}{R}\right)^2 & \frac{x^1 x^2}{R^2} & \frac{x^1 x^3}{R^2} \\ \frac{x^1 x^2}{R^2} & 1 - \left(\frac{x^2}{R}\right)^2 & \frac{x^2 x^3}{R^2} \\ \frac{x^1 x^3}{R^2} & \frac{x^2 x^3}{R^2} & 1 - \left(\frac{x^3}{R}\right)^2 \end{vmatrix} \quad (2)$$

$$= 1 - \left(\frac{x^1}{R}\right)^2 - \left(\frac{x^2}{R}\right)^2 - \left(\frac{x^3}{R}\right)^2 \quad (3)$$

$$= 1 - \frac{R^2}{R^2} \quad (4)$$

$$= 0 \quad (5)$$

So, $dv_{(3)} = 0$ at any point of the null cone giving a zero 3-volume everywhere on that manifold.



7.27 p279 - Exercise 8†

Prove that a polar N -space of constant curvature is oriented if N is odd and unoriented if N is even., but that an antipodal N -space of constant curvature is always oriented.

Let's us first sum up some key-definitions which could be usefull for proving the above assumption.

a) Chapter 4 pages 111-116: *In a space with constant positive curvature, two adjacent geodesics issuing from a point O intersect at a point O' at a distance $s = \frac{\pi}{\sqrt{\epsilon K}}$. If we have $O = O'$, than the space is called **polar** (or elliptic).*

b) The factor $d\tau_{(M)} = |d_{(\beta)}y^\alpha|$ is called the **intrinsic extension of the infinitesimal cell in the subspace V_M** . The following relations exist:

$$d\tau_M^{k_1 \dots k_M} = \nu^{k_1 \dots k_M} d\tau_{(M)}$$

with

$$\nu^{k_1 \dots k_M} = \epsilon^{k_1 \dots k_M} \frac{\partial x^{k_1} \dots x^{k_M}}{\partial y^{\alpha_1} \dots y^{\alpha_M}}$$

$\nu^{k_1 \dots k_M}$ is called the **M-direction of V_M at a point P** .

If $M = N$ then we see that $\nu^{k_1 \dots k_M} = \epsilon^{k_1 \dots k_M}$.

c) page 261: *Comparison of M -cells at two different points A and B in a region R_M of the subspace V_M is achieved as follows: The infinitesimal cell at A , say, is moved in a continuous manner to B along a path C lying in R_M , such that, at each stage of the continuous motion, the intrinsic extension of the cell is non-zero. The orientations of the two cells are then compared at point B .*

d) page 261: *There are, however, regions where the orientations of cells at different points cannot be compared because the procedure adapted above is not unique. Such regions are called unoriented or one-sided.*

Before delving in an attempt, some things are not clear for me. E.g. in c), how can one be sure that such a path exist so that the intrinsic extension does not vanish.



7.28 p279 - Exercise 9

Show that the total volume of a polar 3-space of constant curvature R^{-2} is $\pi^2 R^3$, and that the volume is $2\pi^2 R^3$ if the space is antipodal.

From **4.130** page 118 we know that the line-element for a space of positive constant curvature is

$$ds^2 = dr^2 + R^2 \sin^2 \left(\frac{r}{R} \right) (d\theta^2 + \sin^2 \theta d\phi^2) \quad (1)$$

For the considered metric, we have

$$(a_{mn}) = \begin{pmatrix} 1 & 0 & 0 \\ 0 & R^2 \sin^2 \left(\frac{r}{R} \right) & 0 \\ 0 & 0 & R^2 \sin^2 \left(\frac{r}{R} \right) \sin^2 \theta \end{pmatrix} \quad (2)$$

giving

$$|a_{mn}| = R^4 \sin^4 \left(\frac{r}{R} \right) \sin^2 \theta \quad (3)$$

Using **7.410** with $|d_{(\beta)} y^\alpha| = |d_{(s)} x^k| = dr d\theta d\phi$:

$$dv_{(M)} = R^2 \sin^2 \left(\frac{r}{R} \right) \sin \theta dr d\theta d\phi \quad (4)$$

We can now integrate to get the total volume of the space. As stated for **7.410** we have to note that the distance between two points, when $dr = 0$, vanish when $r = \pi R$ meaning that the integration along the intrinsic variable r must be done in the interval $[0, \pi R]$ in order to avoid double counting in the integration. For a polar space, we have to restrict the integration along θ to $\frac{\pi}{2}$. This gives the volume :

$$V_{(3)} = \int_0^{\pi R} \int_0^{\frac{\pi}{2}} \int_0^{2\pi} R^2 \sin^2 \left(\frac{r}{R} \right) \sin \theta dr d\theta d\phi \quad (5)$$

$$= 2\pi R^3 \underbrace{\int_0^{\pi} \sin^2 \beta d\beta}_{= \frac{1}{2}(\beta - \frac{1}{2} \sin(2\beta)) \Big|_0^{\pi}} \underbrace{\int_0^{\frac{\pi}{2}} \sin \theta d\theta}_{= -\cos \theta \Big|_0^{\frac{\pi}{2}}} \quad (6)$$

$$= \pi^2 R^3 \quad (7)$$

(the first integral in (6) can be found by substituting $\sin^2 x = 1 - \cos^2 x$ and using the cosine sum of angles rule $\cos(\alpha + \beta) = \cos \alpha \cos \beta - \sin \alpha \sin \beta$ with $\alpha = \beta = x$).

◇

For an antipodal space we have to integrate along θ in the interval $[0, \pi]$, which gives a volume twice the volume of a polar plane i.e. $V_{(3)} = 2\pi^2 R^3$.

◆

7.29 p279 - Exercise 10

If r_{mn} is an absolute tensor in 4-space, show that L defined by,

$$L = |r_{mn}|^{\frac{1}{2}}$$

is an invariant density. Discuss the tensor character of f^{mn} and g^{mn} , defined by

$$f^{mn} = \frac{\partial L}{\partial r_{mn}}, \quad g^{mn} = f^{mn} |f^{ks}|^{-\frac{1}{2}}$$

and also of g_{mn} , defined by

$$g_{ms} g^{ns} = \delta_m^n$$

prove that $|g_{mn}| = |f^{mn}|$. (Schrödinger)

As r_{mn} is an absolute tensor then we know from **7.202**

$$|r'_{mn}| = J^2 |r_{st}| \quad (1)$$

Hence, $L = |r_{st}|^{\frac{1}{2}}$ is a relative invariant of weight 1, i.e. a invariant density.

This gives for $f^{mn} = \frac{\partial L}{\partial r_{mn}}$

$$f^{mn} = \frac{\partial |r_{st}|^{\frac{1}{2}}}{\partial r_{mn}} \quad (2)$$

$$= \frac{1}{2} \frac{\Delta^{mn}}{|r_{st}|^{\frac{1}{2}}} \quad (3)$$

with Δ^{mn} the cofactor of the element r_{mn} in the determinant. From exercise 5 in this chapter we know that Δ^{mn} is relative tensor of weight 2. From (3), this gives a weight of $\frac{L^2}{L} = L$. Hence, f^{mn} is contravariant tensor density. Let's look at $g^{mn} = f^{mn} |f^{ks}|^{-\frac{1}{2}}$. Analogous to (1), we have $|f'_{ks}|^{-\frac{1}{2}} = (J^{-2} |f^{mn}|)^{-\frac{1}{2}} = J |f'^{mn}|^{-\frac{1}{2}}$, being an invariant density. So g^{mn} is a relative tensor of weight 2. For g_{ms} we have

$$g_{ms} g^{ns} = \delta_m^n \quad (4)$$

We know that g^{ns} is a relative tensor of weight 2 and (see page 243) δ_m^n a mixed absolute tensor.

So from $g_{ms} g^{ns} = \delta_m^n$, we deduce for the weight W of g_{ms} , $W + 2 = 0$.

Conclusion, g_{ms} is a relative tensor of weight -2 . Finally,

$$g_{ms} g^{ns} = \delta_m^n \quad (5)$$

$$\Rightarrow |g_{ms}| |g^{ns}| = \underbrace{|\delta_m^n|}_{=1} \quad (6)$$

From the definition of g^{mn} we have, nothing that for a matrix $A \in GL_n(\mathbb{R})$, $|ka^{mn}| = k^n |a^{mn}|$, with

in our case $n = 4$:

$$|g^{mn}| = |f^{mn}| \left(|f^{ks}|^{-\frac{1}{2}} \right)^4 \quad (7)$$

$$= |f^{ks}|^{-\frac{1}{2}} |f^{ks}|^{-2} \quad (8)$$

$$= |f^{ks}|^{-1} \quad (9)$$

and (6) becomes

$$|g_{ms}| |f^{ks}|^{-1} = 1 \quad (10)$$

proving the identity.



7.30 p279 - Exercise 11

In a non-metrical space V_4 there is a skew-symmetric absolute tensor field F_{mn} satisfying the partial differential equations

$$F_{mn,r} + F_{nr,m} + F_{rm,n} = 0$$

Show that, if U_2 and W_2 are two-closed 2-spaces in V_4 , deformable into one another with preservation of orientation, then

$$\int_{U_2} F_{mn} d\tau_{(2)}^{mn} = \int_{W_2} F_{mn} d\tau_{(2)}^{mn}$$

First we note that the term "deformable" is not defined precisely in this exercise. So we suppose that the two 3-spaces, U_3 and W_3 enclosed by U_2 and W_2 are diffeomorphic to each other and that this diffeomorphism preserves the orientation and value of the extension between the mapped points, giving $\int_{U_3} d\tau_{(3)}^{mnr} = \int_{W_3} d\tau_{(3)}^{mnr}$.

From **7.505** we have

$$\begin{cases} \int_{U_3} F_{mn,r} d\tau_{(3)}^{mnr} = \int_{U_2} F_{mn} d\tau_{(2)}^{mn} \\ \int_{W_3} F_{mn,r} d\tau_{(3)}^{mnr} = \int_{W_2} F_{mn} d\tau_{(2)}^{mn} \end{cases} \quad (1)$$

The partial differential equations give, using the skew-symmetry of F_{mn} and $d\tau_{(3)}^{mnr}$:

$$\int_{U_3} F_{mn,r} d\tau_{(3)}^{mnr} + \int_{U_3} F_{nr,m} d\tau_{(3)}^{mnr} + \int_{U_3} F_{rm,n} d\tau_{(3)}^{mnr} = \int_{U_3} d\tau_{(3)}^{mnr} \quad (2)$$

$$\Rightarrow \int_{U_3} F_{mn,r} d\tau_{(3)}^{mnr} + \int_{U_3} F_{rn,m} d\tau_{(3)}^{rnm} + \int_{U_3} F_{rm,n} d\tau_{(3)}^{rnm} = \int_{U_3} d\tau_{(3)}^{mnr} \quad (3)$$

$$\Rightarrow 3 \int_{U_3} F_{mn,r} d\tau_{(3)}^{mnr} = \int_{U_3} d\tau_{(3)}^{mnr} \quad (4)$$

$$(1) \quad 3 \int_{U_2} F_{mn} d\tau_{(2)}^{mn} = \int_{U_3} d\tau_{(3)}^{mnr} \quad (5)$$

The same is true for the W_3 space and as we assumed that $\int_{U_3} d\tau_{(3)}^{mnr} = \int_{W_3} d\tau_{(3)}^{mnr}$ we can conclude

$$\int_{U_2} F_{mn} d\tau_{(2)}^{mn} = \int_{W_2} F_{mn} d\tau_{(2)}^{mn}$$



7.31 p280 - Exercise 12

In a flat space V_4 there is a skew-symmetric Cartesian tensor field F_{mn} satisfying the partial differential equations $F_{mn,n} = 0$. Show that if U_3 and W_3 are two closed 3-spaces in V_4 deformable into one another with preservation of the sense of the unit normal n_r , then

$$\int_{U_3} \epsilon(n) F_{rs} n_s dv_{(3)} = \int_{W_3} \epsilon(n) F_{rs} n_s dv_{(3)}$$

The way to go is quite similar to the previous exercise. In this case we assume also that the two 4-spaces, U_4 and W_4 enclosed by U_3 and W_3 are diffeomorphic to each other and that this diffeomorphism preserves the volume of the two shapes, giving $\int_{U_4} dv_{(4)} = \int_{W_4} dv_{(4)}$.

From 7.609 we have (considering $T^n = F_{mn}|_{m=M}$ as a Cartesian vector for a fixed $m = M$):

$$\begin{cases} \int_{U_4} T^n_{|n} dv_{(4)} = \int_{U_3} \epsilon(n) T^r n_r dv_{(3)} \\ \int_{W_4} T^n_{|n} dv_{(4)} = \int_{W_3} \epsilon(n) T^r n_r dv_{(3)} \end{cases} \quad (1)$$

Note that raising the index in T^n is allowed as F_{mn} is Cartesian tensor and that we are in a flat space where we can choose a homogeneous coordinate system. For a Cartesian tensor we can replace the covariant derivative by the partial derivative and using the given differential equation we get

$$\int_{U_4} T^n_{|n} d\tau_{(4)} = \int_{U_4} dv_{(4)} \quad (2)$$

$$\Rightarrow \int_{U_3} \epsilon(n) T^r n_r dv_{(3)} = \int_{U_4} dv_{(4)} \quad (3)$$

The same is true for W_4 . using the assumption $\int_{U_4} dv_{(4)} = \int_{W_4} dv_{(4)}$ and replacint T^n by F_{mn} we get

$$\int_{U_3} \epsilon(n) F_{rs} n_s dv_{(3)} = \int_{W_3} \epsilon(n) F_{rs} n_s dv_{(3)}$$



7.32 p280 - Exercise 13

In a non-metrical space V_3 there is given an absolute covariant vector field v_r . Then the derived vector field $\omega^r = \epsilon^{rmn}v_{n,m}$ determines an invariant direction at each point of V_3 and hence a congruence of curves in V_3 . A tube T is chosen, composed of such curves, and C, C' are two closed curves lying in T , and such that they may be deformed into another without leaving T . Prove that

$$\int_C v_r dx^r = \int_{C'} v_r dx^r$$

the integrals being taken in senses which coincide when one curve is deformed into the other. (Note that this is a generalization of Exercise VI, No.4.)

