

$$\begin{aligned} \frac{d}{dt} \sum_{j,k} A_{jk} \frac{dq_j}{dt} \frac{dq_k}{dt} &= \sum_{j,k} A_{jk} \left(\frac{d^2 q_j}{dt^2} + \frac{dq_j}{dt} \frac{dq_k}{dt} \right) \\ &= \sum_{j,k} A_{jk} \delta_{ji} \frac{dq_k}{dt} + \frac{dq_j}{dt} \delta_{kj} = \sum_k A_{ik} \frac{dq_k}{dt} + \sum_i A_{ki} \frac{dq_i}{dt} \\ &= 2 \sum_i A_{ij} \frac{dq_i}{dt} \\ \frac{\partial T}{\partial \dot{q}_i} &= \frac{\partial L}{\partial \dot{q}_i} = P_i = \sum_j A_{ij} \frac{dq_j}{dt} \\ \sum_i P_i \frac{dq_i}{dt} &= \sum_i \left(\sum_j A_{ij} \frac{dq_j}{dt} \right) \frac{dq_i}{dt} = \sum_{i,j} A_{ij} \frac{dq_i}{dt} \frac{dq_j}{dt} = 2E_K \end{aligned}$$

Conservation Theorems Revisited

conservation of energy

time is homogenous within an inertial reference frame

therefore, the Lagrangian that describes a closed system cannot depend

$$\frac{\partial L}{\partial t} = 0 = \sum_j \frac{\partial L}{\partial \dot{q}_j} \frac{dq_j}{dt} + \sum_j \frac{\partial L}{\partial q_j} \frac{d^2 q_j}{dt^2}$$

$$\text{and } \frac{\partial L}{\partial \dot{q}_j} = \frac{d}{dt} \frac{\partial L}{\partial q_j}$$

$$\Rightarrow \frac{\partial L}{\partial t} = \sum_j \frac{d \dot{q}_j}{dt} \frac{d}{dt} \frac{\partial L}{\partial \dot{q}_j} + \sum_j \frac{\partial L}{\partial q_j} \frac{d^2 q_j}{dt^2}, \quad \frac{dL}{dt} - \sum_j \frac{d}{dt} \left(\frac{d \dot{q}_j}{dt} \frac{\partial L}{\partial \dot{q}_j} \right) = 0$$

$$\text{so that } \frac{d}{dt} \left(L - \sum_j \frac{d \dot{q}_j}{dt} \frac{\partial L}{\partial \dot{q}_j} \right) = 0, \quad L - \sum_j \frac{d \dot{q}_j}{dt} \frac{\partial L}{\partial \dot{q}_j} = -H = \text{constant}$$

$$\frac{\partial L}{\partial \dot{q}_j} = \frac{\partial (E_K - L)}{\partial \dot{q}_j} = \frac{\partial E_K}{\partial \dot{q}_j}$$

$$\Rightarrow (E_K - L) - \sum_j \frac{d \dot{q}_j}{dt} \frac{\partial E_K}{\partial \dot{q}_j} = -H$$

$$\Rightarrow E_K - L - 2E_K = -H$$

$$\Rightarrow E_K + L = E_t = H = \text{constant}$$

Hamiltonian

$H = E_{\text{total}}$ if the following conditions are

1. the equations of the transformation
2. the coordinates