

Harmonic Oscillation

$$\omega_0 = \sqrt{\frac{k}{m}}$$

$$C = \sqrt{A^2 + B^2}$$

$$\phi = \tan^{-1} \left[\frac{-B}{A} \right]$$

Undamped HO: $z(t) = C \cos(\omega_0 t + \phi)$

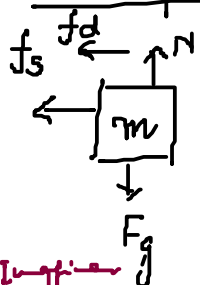


* Energy $\Rightarrow E(t) = K \cdot E(t) + P \cdot E(t)$
 $= \frac{1}{2} m v^2 + \frac{1}{2} k x^2$

$$= \frac{1}{2} m \left[-C \omega_0 \sin(\omega_0 t + \phi) \right]^2 + \frac{1}{2} k \left[C \cos(\omega_0 t + \phi) \right]^2$$

$$E(t) = \frac{1}{2} m C^2 \omega_0^2$$

$$\langle K \cdot E \rangle = \frac{1}{4} m C^2 \omega_0^2 = \langle P \cdot E \rangle$$

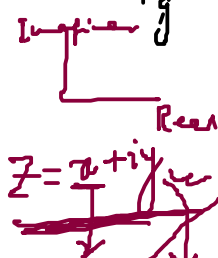
Damped HO \Rightarrow 

$$\vec{F} = \vec{f}_s + \vec{f}_d + \vec{N} + \vec{F}_g$$

+ more forces

$$m \ddot{x} = -k x(t) - b \dot{x}(t)$$

$$\Rightarrow \ddot{x} + \frac{b}{m} \dot{x}(t) + \frac{k}{m} x = 0$$



$$\ddot{z} + \gamma \dot{z} + \omega_0^2 z = 0$$

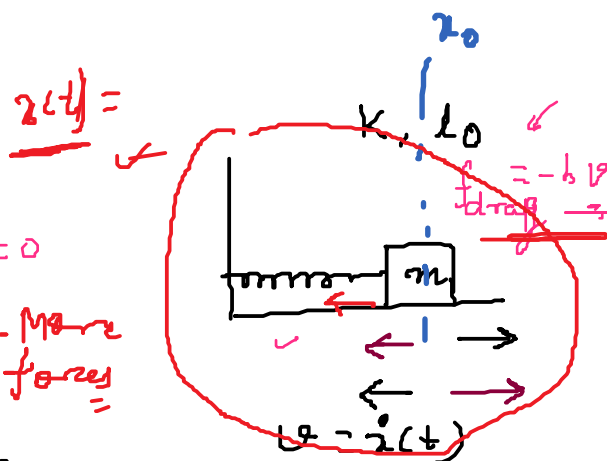
$$\gamma = \frac{b}{m}$$

$$\omega_0^2 = \frac{k}{m}$$

$$x(t) = \text{Re} [z(t)] = \text{Re} [z_0 e^{i\alpha t}]$$

$$\Rightarrow \ddot{z} + \gamma \dot{z} + \omega_0^2 z = 0$$

$$\rightarrow [\alpha^2 + i\gamma\alpha + \omega_0^2] (z_0 e^{i\alpha t}) = 0$$



$$f_d = -b v$$

$b = \text{damping constant}$

$$z(t) = \text{Re} \left[C e^{i(\omega_0 t + \phi)} \right]$$

$$= C \cos(\omega_0 t + \phi)$$

$$\alpha \rightarrow \gamma, \omega_0, m, k$$

$$\rightarrow [\alpha^2 + i\gamma\alpha + \omega_0^2](z_0 e^{\alpha t}) = 0$$

m, k

$$\Rightarrow \alpha^2 - i\gamma\alpha + \omega_0^2 = 0$$

$$\alpha = \frac{i\gamma \pm \sqrt{-\gamma^2 + 4\omega_0^2}}{2}$$

$$ax^2 + bx + c = 0$$

$$\Downarrow$$

$$x = \frac{-b \pm \sqrt{b^2 - 4ac}}{2a}$$

$$\alpha = \frac{i\gamma}{2} \pm \sqrt{\omega_0^2 - \frac{\gamma^2}{4}}$$

$$\omega_0^2 = \frac{k}{m}, \quad \gamma = \frac{b}{m}$$

b : damping constant.

$$= \frac{i\gamma}{2} \pm \sqrt{\frac{k}{m} - \frac{b^2}{4m^2}}$$

- ① $\omega_0^2 > \frac{\gamma^2}{4}$: Lightly damped oscillator
- ② $\omega_0^2 = \frac{\gamma^2}{4}$: Critically damped oscillator
- ③ $\omega_0^2 < \frac{\gamma^2}{4}$: Heavily damped oscillator

Lightly damped oscillator $\Rightarrow \omega_0^2 > \frac{\gamma^2}{4}, \quad \alpha = \frac{i\gamma}{2} \pm \sqrt{\omega_0^2 - \frac{\gamma^2}{4}}$

$\omega^2 = \omega_0^2 - \frac{\gamma^2}{4}$ trc number

$$\rightarrow Z_+(t) = Z_{0+} e^{i[\alpha t]} = Z_{0+} e^{-\frac{\gamma}{2}t} e^{i\omega t}$$

$$Z_-(t) = Z_{0-} e^{-\frac{\gamma}{2}t} e^{-i\omega t}$$

$$e^{i\omega t} = \cos \omega t + i \sin \omega t$$

$$e^{-i\omega t} = \cos \omega t - i \sin \omega t$$

$$Z_1(t) = \frac{1}{2} [Z_+(t) + Z_-(t)]$$

$$= \frac{1}{2} [Z_{0+} e^{-\frac{\gamma}{2}t} e^{i\omega t} + Z_{0-} e^{-\frac{\gamma}{2}t} e^{-i\omega t}]$$

$$= e^{-\frac{\gamma}{2}t} [\frac{Z_{0+}}{2} e^{i\omega t} + \frac{Z_{0-}}{2} e^{-i\omega t}]$$

$$Z_{0+} = Z_{0-}$$

$$z(t) = z_0 e^{-\frac{\gamma}{2}t} \left[\frac{e^{i\omega t} + e^{-i\omega t}}{2} \right]$$

$$\underline{z_{0+} = z_{0-}}$$

$$z_1(t) = z_0 e^{-\frac{\gamma}{2}t} \cos \omega t$$

$$z_2(t) = \frac{1}{2} [z_{0+} - z_{0-}] = \frac{1}{2} z_0 \left[\frac{e^{i\omega t} - e^{-i\omega t}}{2} \right]$$

$i \sin \omega t$

$$z(t) = z_0 e^{-\frac{\gamma}{2}t} \cos \omega t + i z_0 e^{-\frac{\gamma}{2}t} \sin \omega t$$

$$z(t) = e^{-\frac{\gamma}{2}t} [z_0 \cos \omega t + i z_0 \sin \omega t]$$

$$x(t) = \text{Re}[z(t)] = C e^{-\frac{\gamma}{2}t} \cos(\omega t + \phi)$$

$$\underline{x(t) = C e^{-\frac{\gamma}{2}t} \cos(\omega t + \phi)}$$

$$\omega = \sqrt{\omega_0^2 - \frac{\gamma^2}{4}}$$

Initial Cond \Rightarrow 1. $z(0) = z_{\text{initial}} = z_0$

$$\underline{x(0) = x_{\text{initial}} = C \cos \phi}$$

2. $\dot{x}(0) = 0$, $\dot{x}(t) = C \left(-\frac{\gamma}{2}\right) \cos(\omega t + \phi) e^{-\frac{\gamma}{2}t} - C \omega \sin(\omega t + \phi) e^{-\frac{\gamma}{2}t}$

$$C e^{-\frac{\gamma}{2}t} \cdot \omega \cdot \sin(\omega t + \phi) e^{-\frac{\gamma}{2}t}$$

$$\dot{x}(0) = -C \frac{\gamma}{2} \cos \phi - C \omega \sin \phi = 0$$

$$\Rightarrow \boxed{\tan \phi = -\frac{\gamma}{2\omega}}$$

$$x(t) = x_{\text{initial}} e^{-\gamma/2} \cos(\omega t + \phi)$$



→ t

~~Damped~~ $\underline{\omega} T = 2\pi$