

A rational mechanics course where everything is made with Python code

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New Media Pedagogy 23: research trends,
methodological challenges and succesful
implementations

21-24 november 2023



JAGIELLONIAN UNIVERSITY
IN KRAKÓW



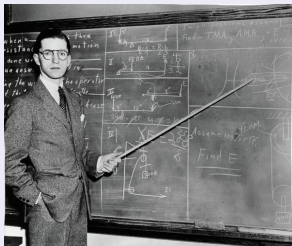
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Value students and professors time

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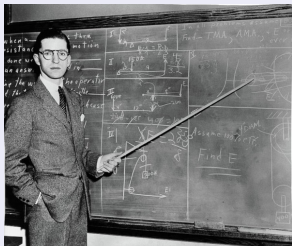


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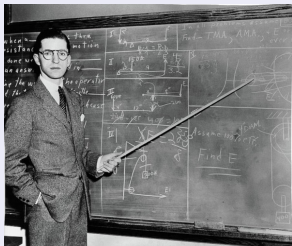


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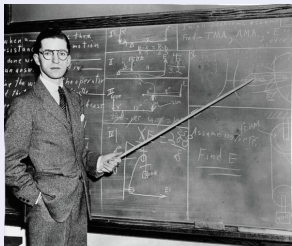


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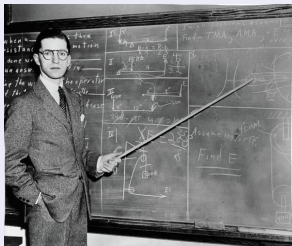


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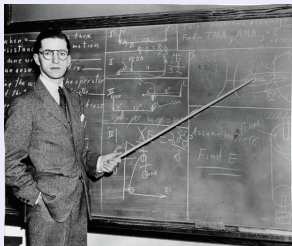


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```
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```

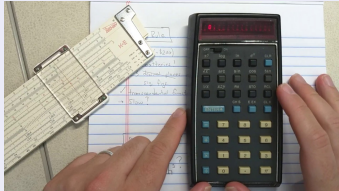
Digital course material with embedded code

- Professor: ideas $\xrightarrow{\text{updates}}$ code/theory in repository

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```
[14]: sistemaEcuaciones = [  
      x_EL,  
      phi_EL,  
    ]  
variablesDespeje = [x.diff(t,2), phi.diff(t,2)] # despejar aceleraciones generalizadas  
variablesDespeje_sol= sym.nonlinsolve(sistemaEcuaciones, variablesDespeje ).args[0]
```

```
[15]: x_pp = sym.Eq(variablesDespeje[0], variablesDespeje_sol.args[0] ) # [m s-2]  
phi_pp = sym.Eq(variablesDespeje[1], variablesDespeje_sol.args[1] ) # [m s-2]  
x_pp, phi_pp
```

$$[15]: \left(\begin{array}{l} \ddot{x} = \frac{-\ell g m_2 \sin(\phi) + \frac{\ell m_2 (\ell m_2 \cos(\phi) \dot{\phi}^2 + g m_1 + g m_2) \sin(\phi)}{m_1 + m_2 \sin^2(\phi)}}{\ell m_2 \cos(\phi)}, \ddot{\phi} = -\frac{(\ell m_2 \cos(\phi) \dot{\phi}^2 + g m_1 + g m_2) \sin(\phi)}{\ell (m_1 + m_2 \sin^2(\phi))} \end{array} \right)$$

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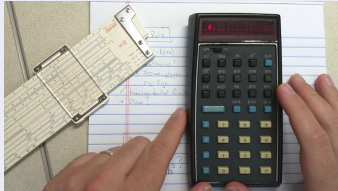
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 - ▶ Employing numerical calculus they solve what is impossible in a blackboard/paper



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Papert (1980) “...the best learning takes place when the learner takes charge”

- An example problem is solved by the professor provided code
- The student **recycles** it to solve other related problems
- Gradually becoming autonomous by reusing not the provided but his own code

Tools — Jupyter notebook: text + equations + executable code

The screenshot shows a Jupyter Notebook window with the title "PÉNDULO EN HEBRADOS SOLVED.IPYNB". The left sidebar contains a table of contents with the following items:

- Péndulo enhebrado en aro
- Enunciado
- 1. Construya el Lagrangiano y la(s) función(es) de ligadura
- 2. Calcule las ecuaciones de Euler-Lagrange
- 3. Obtenga una expresión para la tensión que ejerce la barra
- 4. Grafique la tensión en los primeros diez segundos de la dinámica.

The main content area displays the following text and code:

3. Obtenga una expresión para la tensión que ejerce la barra

$$Q_d = \lambda_1 \frac{\partial f_1}{\partial d} = \lambda_1$$

Por tanto hay que resolver el sistema con las 3 ecuaciones de Euler-Lagrange y la única de ligadura para determinar λ_1 . Esta última hay que resolverla para su caso homogéneo y expresar su derivada segunda para que esté en el mismo orden que las de Euler-Lagrange, a fin de cuentas estamos resolviendo sistemas diferenciales de 2.º orden.

```
[14]: f_1
```

$$f_1 = -l + d$$

Determinamos también $\ddot{\theta}_1$ y $\ddot{\theta}_2$ pues serán necesarias para los cálculos numéricos posteriores.

```
[15]: sistema = [theta1_EL.expand(),
               theta2_EL.expand(),
               d_EL.expand(),
               sym.Eq(f_1.rhs.diff(t,2), 0), # esto es igual a d punto punto = 0
               ]
variables = [theta1.diff(t,2), theta2.diff(t,2), lambda_1]
variables_sol = sym.nonlinsolve(sistema, variables).args[0]
```

```
[16]: lambda_1_sol = sym.Eq(lambda_1, variables_sol.args[2])
      lambda_1_sol.simplify()
```

```
[16]:
```

$$\lambda_1 = \frac{m \left(2a \cos(\theta_1 - \theta_2) \dot{\theta}_1^2 + g \cos(2\theta_1 - \theta_2) + g \cos(\theta_2) + 2d \ddot{\theta}_2 - 2\ddot{d} \right)}{\cos(2\theta_1 - 2\theta_2) - 3}$$

Tools — Google Colaboratory runs Jupyter notebooks on-line

- The platform allows professors to edit and comment on the work of students.
- Students can collaborate remotely, working on the same Jupyter notebook.

The screenshot displays a Google Colaboratory notebook titled "07 No conservativas | ej4". The interface includes a top navigation bar with options like "Archivo", "Editar", "Ver", "Insertar", "Entorno de ejecución", "Herramientas", and "Ayuda". A sidebar on the left shows file explorer icons. The main area contains a Jupyter cell with Python code using SymPy for symbolic computation. The code defines a potential energy function V and calculates the Lagrangian L . Below the code, the resulting mathematical expressions for V and L are shown. A comment box on the right, by Victor Alexis Bettachini, discusses the physical interpretation of the spring constants k_1 and k_2 . The notebook also shows a section for "Ecuaciones de Euler" and a prompt "Para x".

```
[ ] # Energía potencial
m1_V = - (m1* g* (- N.y)).dot(m1_r)
# pot_k1 = unMedio* ( -k1* ((l10 + x1)* (sym.cos(theta) - sym.sin(theta)) )**2 ) # mal
pot_k1 = unMedio* k1* (l10 + x1)**2 # Lo escribi yo
# pot_k2 = unMedio* -k2* (l20 + x)**2
pot_k2 = unMedio* k2* (l20 + x)**2
V = sym.Eq(sym.Symbol('V'), m1_V + pot_k1 + pot_k2 ) #agrega el potencial elastico k en la ecuacion
V
```

$$V = gm_1(-l_{10} - x_1)\sin(\theta) + \frac{k_1(l_{10} + x_1)^2}{2} + \frac{k_2(l_{20} + x)^2}{2}$$

▼ Lagrangiano

```
[ ] L = sym.Eq(sym.Symbol('\mathcal{L}'), (T.rhs - V.rhs))
L
```

$$\mathcal{L} = -gm_1(-l_{10} - x_1)\sin(\theta) - \frac{k_1(l_{10} + x_1)^2}{2} - \frac{k_2(l_{20} + x)^2}{2} + \frac{(m_0 + m_1)(2\cos(\theta)\dot{x}\dot{x}_1 + \dot{x}^2 + \dot{x}_1^2)}{2}$$

ECUACIONES DE EULER

Para x

Victor Alexis Bettachini 31 de may. de 2021
- El estiramiento del resorte de k_1 es colineal con x_1 . No tienen sentido pensar en proyecciones (si es lo que hiciste, que realmente no entiendo).
- ¿Porque negativos los k?

Tools — All course material in a GitHub repository

- Clearly organised, freely accesible, and easy to update.
- Google Colaboratory loads Jupyter notebooks directly from GitHub.

The screenshot shows the GitHub interface for the repository 'bettachini / UNLaM_MecanicaGeneral'. The repository has 1 star and 0 forks. The main content area displays a list of files and folders, including '00Generalidades', '01Newtoniana', '02NoInercial', '03Energia', '04EulerLagrange', '05Simulación', '06FuerzasLigadura', '07NoConservativas', '10TensorInercia', and '11RotaciónEuler'. Each item shows its name, a description, and the time since the last update. The right sidebar contains an 'About' section with a description of the repository, a 'Readme' link, a 'View license' link, and a 'Releases' section indicating no releases are published.

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bettachini / UNLaM_MecanicaGeneral

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master 1 branch 0 tags

Go to file Add file Code

bettachini slides erste	3167a56 yesterday	188 commits
00Generalidades	parcial retrasado	last month
01Newtoniana	09TensorInercia update	2 days ago
02NoInercial	cc by-nc-sa	last month
03Energia	cc by-nc-sa	last month
04EulerLagrange	Atwood compuestas	16 days ago
05Simulación	09TensorInercia update	2 days ago
06FuerzasLigadura	09 update lpyngo	4 days ago
07NoConservativas	07NoConservativas noConservativasEjemplos.lpynb	16 days ago
10TensorInercia	10TensorInercia lpynb update 2	2 days ago
11RotaciónEuler	numbering	2 days ago

About

Repositorio de la asignatura "Mecánica General" de la carrera de grado en Ingeniería mecánica de la Universidad Nacional de La Matanza.

physics mechanical-engineering fisica

meccanica lagrangian vibrations

mechanics-of-solids

Readme

View license

Releases

No releases published

Create a new release

Tools — From the 1st class — L^AT_EX: concise mathematical notation

- L^AT_EX typesetting follows strictly the standards of the American Mathematical Society

Considero que el potencial V es nulo en el origen de coordenadas, es decir que donde se encuentra su mínimo $\varphi = 0$, $V(\varphi = 0) = -mg\ell$ y por tanto

$$V(\varphi) = mg(-\ell \cos \varphi) = -mg\ell \cos \varphi,$$

Como vemos la aproximación funciona bastante bien. Conformes con ella calculamos la fuerza

$$\vec{F} = -\vec{\nabla}V = -\left(\frac{\partial}{\partial r}, \frac{1}{r}\frac{\partial}{\partial \varphi}, \frac{\partial}{\partial z}\right)V(\varphi)$$

Pero solo nos interesa expresar la 2.a ley de Newton para lo que pasa en $\hat{\varphi}$

$$m\ddot{\vec{r}} \cdot \hat{\varphi} = -\frac{1}{r}\frac{\partial}{\partial \varphi}V(\varphi)$$

En el lado izquierdo de la expresión de la aceleración en cilíndricas $\ddot{\vec{r}} = (\ddot{r} - r\dot{\varphi}^2)\hat{r} + (r\dot{\varphi}^2 + r\ddot{\varphi})\hat{\varphi} + \ddot{z}\hat{z}$, nos quedamos solo con la componente en $\hat{\varphi}$,

$$\ddot{\vec{r}} \cdot \hat{\varphi} = r\dot{\varphi}^2 + r\ddot{\varphi}$$

y como el hilo del péndulo es rígido e inextensible $r \equiv \ell$ solo queda de esto

$$\ddot{\vec{r}} \cdot \hat{\varphi} = \ell \ddot{\varphi}$$

En el lado derecho la derivada del potencial respecto a φ es

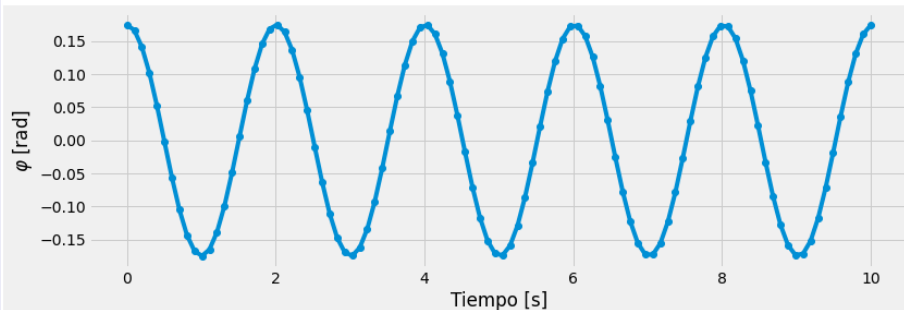
$$\frac{\partial}{\partial \varphi}V(\varphi) = mg\ell \sin(\varphi)$$

Tools — 1st class — Matplotlib: precise and reproducible graphics

- Explicit Python code for producing graphics. Students are enticed to play with it.

```
# graficación
fig, ax = plt.subplots(figsize=(12, 4))
ax.plot(tiempos, phi(tiempos), 'o-')
ax.set_xlabel('Tiempo [s]')
ax.set_ylabel(r'$\varphi$ [rad]')
```

```
Text(0, 0.5, '$\varphi$ [rad]')
```



Tools — 3rd class — SymPy: symbolic calculations

- Students effort centred on new subjects by freeing them of calculus and algebraic tasks.

```
[8]: m2_v_cuadrado = m2_v.dot(m2_v)
     m2_v_cuadrado
```

```
[8]:  $\ell^2 \sin^2(\varphi) \dot{\varphi}^2 + (\ell \cos(\varphi) \dot{\varphi} + \dot{x})^2$ 
```

Con esto la energía cinética queda

$$\begin{aligned} T(\dot{x}_1, \varphi, \dot{\varphi}) &= \frac{m_1}{2} \left(\dot{r}_1 \right)^2 + \frac{m_2}{2} \left(\dot{r}_2 \right)^2 \\ &= \frac{m_1}{2} \dot{x}^2 + \frac{m_2}{2} (\dot{x}^2 + 2\dot{x}\ell \cos \varphi \dot{\varphi} + \ell^2 \dot{\varphi}^2) \end{aligned}$$

```
[9]: # Energía cinética
     unMedio = sym.Rational(1,2) # Rational: fracción de enteros, alternatively podría haberse usado 0.5
     m1_T = unMedio*m1*m1_v_cuadrado
     m2_T = unMedio*m2*m2_v_cuadrado
     T = sym.Eq(sym.Symbol('T'), (m1_T + m2_T) ) # simplify: simplifica usando factor común y otras operaciones
     T
```

```
[9]: 
$$T = \frac{m_1 \dot{x}^2}{2} + \frac{m_2 (\ell^2 \sin^2(\varphi) \dot{\varphi}^2 + (\ell \cos(\varphi) \dot{\varphi} + \dot{x})^2)}{2}$$

```

Tools — 4th class — Equations for Lagrangian dynamics

Ecuaciones de Euler-Lagrange

Para x

```
[8]: x_EL = sym.Eq(L.rhs.diff(x) - L.rhs.diff(x.diff(t)).diff(t), 0).simplify() # ecuación igualando a cero  
x_EL
```

$$[8]: m_1 \ddot{x} + m_2 \left(-\ell \sin(\phi) \dot{\phi}^2 + \ell \cos(\phi) \ddot{\phi} + \ddot{x} \right) = 0$$

Esta es una ecuación diferencial lineal de segundo orden homogénea. De aquí podría despejarse \ddot{x}

```
[9]: sym.Eq(x.diff(t,2),  
          list( sym.solve(x_EL, x.diff(t,2) ) ) [0] # solveset devuelve un set, que convertimos a lista  
          ) # aceleración = x punto punto [m s-2]
```

$$[9]: \ddot{x} = \frac{\ell m_2 \left(\sin(\phi) \dot{\phi}^2 - \cos(\phi) \ddot{\phi} \right)}{m_1 + m_2}$$

Pero queda en función de otra aceleración $\ddot{\phi}$.

Para ϕ

```
[10]: phi_EL = sym.Eq(L.rhs.diff(phi) - L.rhs.diff(phi.diff(t)).diff(t), 0).simplify() # ecuación igualando a cero  
phi_EL
```

Tools — 4th class — Automatisation of resolutions

- Mathematical complexity doesn't limit the scope of tackled mechanical problems.

```
[14]: sistemaEcuaciones = [  
        x_EL,  
        phi_EL,  
    ]  
variablesDespeje = [x.diff(t,2), phi.diff(t,2)] # despejar aceleraciones generalizadas  
variablesDespeje_sol = sym.nonlinsolve(sistemaEcuaciones, variablesDespeje ).args[0]
```

```
[15]: x_pp = sym.Eq(variablesDespeje[0], variablesDespeje_sol.args[0] ) # [m s-2]  
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x_pp, phi_pp
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$$[15]: \left(\ddot{x} = \frac{-\ell g m_2 \sin(\phi) + \frac{\ell m_2 (\ell m_2 \cos(\phi) \dot{\phi}^2 + g m_1 + g m_2) \sin(\phi)}{m_1 + m_2 \sin^2(\phi)}}{\ell m_2 \cos(\phi)}, \ddot{\phi} = -\frac{(\ell m_2 \cos(\phi) \dot{\phi}^2 + g m_1 + g m_2) \sin(\phi)}{\ell (m_1 + m_2 \sin^2(\phi))} \right)$$

Tools — 5th class — SciPy: numerical computation of results

```
[22]: # defino una función con el sistema de derivadas
# t : no se usa en este sistema pero lo dejamos para uso posterior
# y : lista de estado con [y[0], y[1], y[2], y[3]]
# y[0]: x
# y[1]: x punto
# y[2]: phi
# y[3]: phi punto
# dydt : lista de derivadas
def y_punto(t, y):
    dydt = [y[1],
            x_pp_numpy(y[0], y[1], y[2], y[3]),
            y[3],
            phi_pp_numpy(y[0], y[1], y[2], y[3]),
            ]
    return dydt

[23]: # Integración de a pasos en el tiempo
y_ode2 = solve_ivp(y_punto, (t_rango[0], t_rango[-1]), y_inicial, t_eval = t_rango)

[25]: y_ode2.y[0]

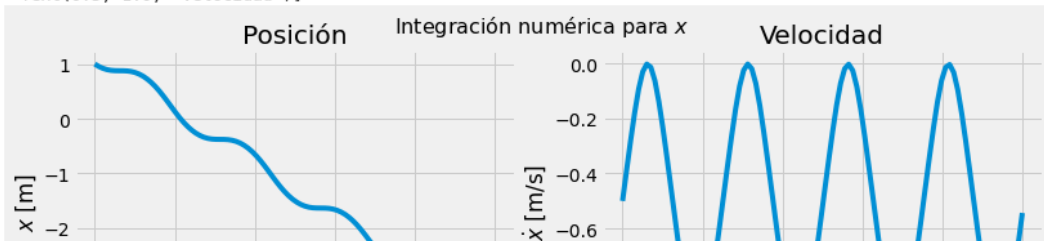
[25]: array([ 1.          ,  0.95510744,  0.92131146,  0.89820932,  0.88468059,
            0.87877042,  0.87745354,  0.87702754,  0.87352768,  0.86357726,
            0.84474673,  0.81565733,  0.77559949,  0.72423163,  0.66166451,
```

Tools — 5th class — Graphical analysis of numerical results

```
[26]: solucion = y_ode2
      nombreCoordenada = 'x'

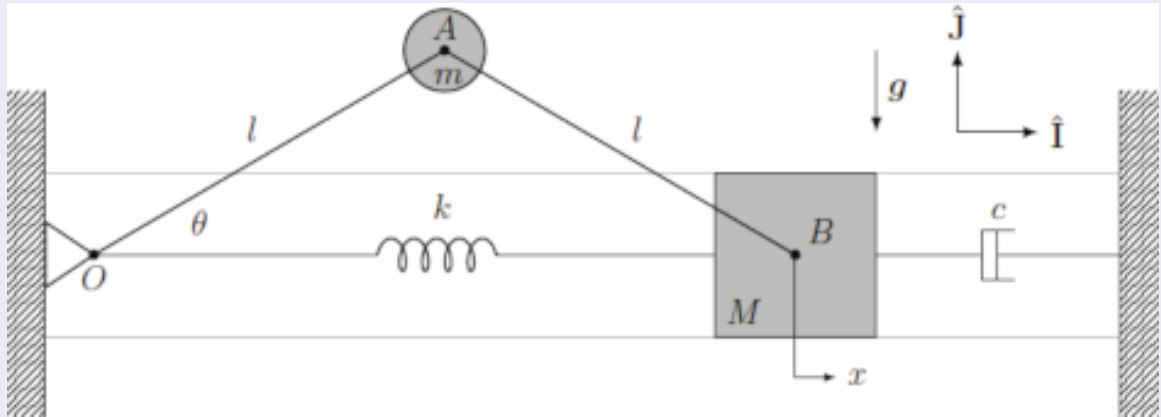
      fig, ax = plt.subplots(nrows= 1, ncols= 2, squeeze=False, figsize=(12, 4)) # dos figuras en la misma fila
      fig.suptitle('Integración numérica para '$'+ nombreCoordenada + '$', fontsize=16)
      ax[0,0].plot(solucion.t, solucion.y[0]) # posición x
      ax[0,0].set(xlabel='t [s]', ylabel='$'+ nombreCoordenada+ '$ [m]', title='Posición')
      ax[0,1].plot(solucion.t, solucion.y[1]) # velocidad x
      ax[0,1].set(xlabel='t [s]', ylabel='$\dot{x}$ [m/s]', title='Velocidad')
```

```
[26]: [Text(0.5, 0, 't [s]'),
      Text(0, 0.5, '$\dot{x}$ [m/s]'),
      Text(0.5, 1.0, 'Velocidad')]
```



Tools — 7th class — Adding complexity

- Code from previous classes is **recycled** to model more realistic devices.



Tools — 8th class — GitHub Copilot: AI assistance for coding

- Now that the students grasp the basics they're invited to take advantage of AI
- After commenting in plain text what they need code is suggested

```
lagrangiano = (T.rhs - V.rhs).expand()
t = sym.Symbol('t') # como se deriva respecto al tiempo con la función diff se declara t como símbolo
return sym.Eq(
    lagrangiano.diff(coordenadaGeneralizada)
    - lagrangiano.diff(coordenadaGeneralizada.diff(t)).diff(t)
    , 0
).simplify()
```

[21]

```
x1_EL = eulerLagrange(T, V, x1)
x1_EL
```

[22]

$$\dots \quad \frac{\pi^2 M \ddot{x}_1}{2} - gm_1 + gm_2 + m_1 \ddot{x}_1 + m_2 \ddot{x}_1 = 0$$

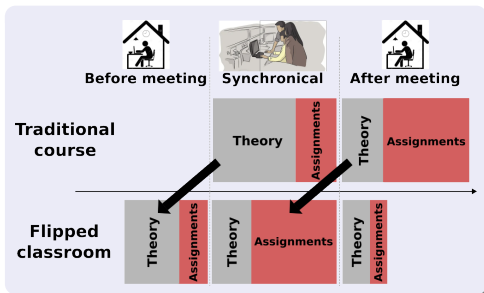
Esta es una ecuación diferencial lineal de segundo orden homogénea. De aquí se puede despejar \ddot{x}

▷ ▾

```
#Despejar x1PuntoPunto
x1PuntoPunto = sym.solve(x1_EL, x1.diff(t, t)).args[0]
```

Methodology — Weekly cycle of our flipped classroom

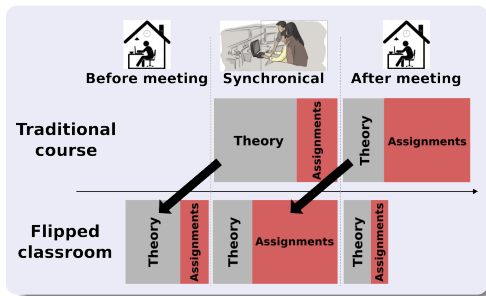
- New theory (Jupyter notebooks and videos) and assignments published on-line



	Synchronic	Theory	Assignments
Before		Read and apply	Start them
During		Consultations	Complete them
After		Additional consultations	TA's corrections

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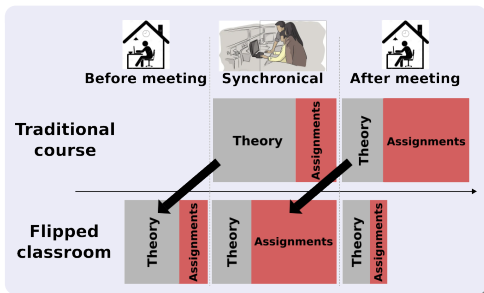
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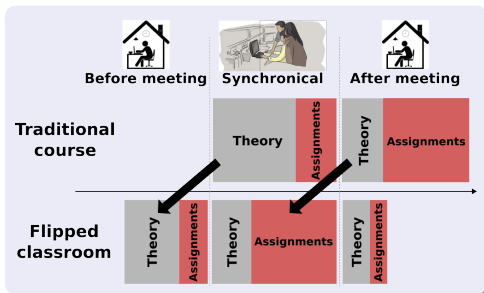
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- New theory (Jupyter notebooks and videos) and assignments published on-line
- Previous week assignments **must** be turned-in for scoring
- On-line 24/7 **asynchronous** consultations that are **public** to other students
- **synchronous** meetings with TA's to finish assignments



	Synchronic	Theory	Assignments
Before		Read and apply	Start them
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Methodology — Google Colaboratory: asynchronic remote assistance

 07 No conservativas | ej4 ☆

Archivo Editar Ver Insertar Entorno de ejecución Herramientas Ayuda [Se editó por última vez: 3 de junio](#)

+ Código + Texto

Conectar ▾ Editando ^

```
[ ] # Energía potencial
m1_V = - (m1* g* (- N.y)).dot(m1_r)
# pot_k1 = unMedio* ( -k1* ((l10 + x1)* (sym.cos(theta) - sym.sin(theta)) )**2 ) # mal
pot_k1 = unMedio* k1* (l10 + x1)**2 # Lo escribí yo
# pot_k2 = unMedio* -k2* (l20 + x)**2
pot_k2 = unMedio* k2* (l20 + x)**2
V = sym.Eq(sym.Symbol('V'), m1_V + pot_k1 + pot_k2 ) #agrega el potencial elastico k en la ecuacion
V
```

$$V = gm_1(-l_{10} - x_1)\sin(\theta) + \frac{k_1(l_{10} + x_1)^2}{2} + \frac{k_2(l_{20} + x)^2}{2}$$

▼ Lagrangiano

```
[ ] L = sym.Eq(sym.Symbol('\mathcal{L}'), (T.rhs - V.rhs))
L
```

$$\mathcal{L} = -gm_1(-l_{10} - x_1)\sin(\theta) - \frac{k_1(l_{10} + x_1)^2}{2} - \frac{k_2(l_{20} + x)^2}{2} + \frac{(m_0 + m_1)(2\cos(\theta)\dot{x}\dot{x}_1 + \dot{x}^2 + \dot{x}_1^2)}{2}$$

ECUACIONES DE EULER

Para x

Comentar

Compartir

Victor Alexis Bettachini

31 de may. de 2021

(editado el 31 de may. de 2021)

Resolver

- El estiramiento del resorte de k_1 es colineal con x_1 . No tienen sentido pensar en proyecciones (si es lo que hiciste, que realmente no entiendo).

- ¿Porque negativos los k ?

Victor Alexis Bettachini

31 de may. de 2021

Resolver

vbettachini@unlam.edu.ar

A code centred mechanics subject

2023-11-23

18 / 21

Summary

A course centred on code

- Material: text + equations + executable code in digital notebooks in a repository

Flipped classroom

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- Synchronical meetings: TA's personal assistance for completing assignments

Thank You!

UNLaM research grant, C2-ING-109