
Damped Pendulum — With Animated Graphics

Started in class, February 7, 2025, and finished as Problem Set 6 for February 11.

This is our sixth numerical methods notebook.

Damped Pendulum

Angular Acceleration α

```
In[786]:=  
gravity = 9.80665;  
(* the value of gravity in units of meters / seconds-squared *)  
length = 0.24840;  
(* A pendulum whose length is 9.7795 inches converted to meters *)  
(* The natural frequency of such a  
pendulum provided the swings are not large: *)  
omega0 = Sqrt[gravity / length];  
gamma = 0.03;  
(* A real pendulum swinging in air typically has a small gamma. *)  
period = 2 Pi / omega0;  
(* The length was chosen so that the period is 1 second. To be *)  
(* precise, 2 Pi / omega0 = 0.999989,  
and 2 Pi / Sqrt[omega0^2-gamma^2] = 1.000000. *)  
alpha[t_, theta_, omega_] := -omega0^2 Sin[theta] - 2 gamma omega;
```

Simulation Parameters

```
In[792]:=  
tInitial = 0.0;  
tFinal = 50.0;  
steps = 200 000;  
deltaT = (tFinal - tInitial) / steps;
```

Initial Angle and Angular Velocity

Let's let the pendulum be initially held still at 10° and gently released:

```
In[796]:=  
thetaInitial = 10 °;  
omegaInitial = -gamma thetaInitial;  
(* gamma is small, and this is only  $0.3^\circ$  / second. *)  
(* Putting in the small initial velocity makes  
the approximate theoretical solution simplify. *)  
initialConditions = {tInitial, thetaInitial, omegaInitial};
```

General Second-Order Runge-Kutta — Damped Pendulum Theory Recap

So you don't have to flip back to the damped pendulum theory handout, I'll recapitulate:

$$t^* = t + \lambda \Delta t$$

$$\theta^* = \theta(t_i) + \omega(t_i) \cdot \lambda \Delta t$$

$$\omega^* = \omega(t_i) + \alpha(t_i, \theta(t_i), \omega(t_i)) \cdot \lambda \Delta t$$

$$t_{i+1} = t_i + \Delta t$$

$$\omega(t_{i+1}) = \omega(t_i) + \left(\left(1 - \frac{1}{2\lambda} \right) \alpha(t_i, \theta(t_i), \omega(t_i)) + \frac{1}{2\lambda} \alpha(t^*, \theta^*, \omega^*) \right) \cdot \Delta t$$

$$\theta(t_{i+1}) = \theta(t_i) + (\omega(t_i) + \omega(t_{i+1})) \frac{\Delta t}{2}$$

General Second-Order Runge-Kutta — Implementation

The implementation of the damped pendulum is almost the same as the damped oscillator. You are just making the replacements $x \rightarrow \theta$, $v \rightarrow \omega$, and $a \rightarrow \alpha$.

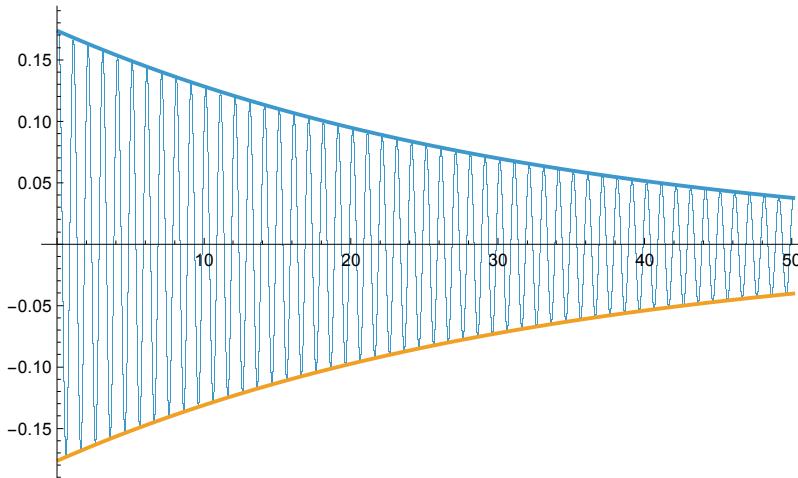
```
In[799]:= lambda = 1;
rungeKutta2[cc_] := (
  (* Extract time, angle, and angular velocity from the list *)
  curTime = cc[[1]];
  curAngle = cc[[2]];
  curAngularVelocity = cc[[3]];
  (* Compute tStar, xStar, vStar *)
  tStar = curTime + lambda deltaT;
  thetaStar = curAngle + curAngularVelocity lambda deltaT;
  omegaStar =
    curAngularVelocity + alpha[curTime, curAngle, curAngularVelocity] lambda deltaT;
  (* Implement General Second-Order Runge-Kutta *)
  newTime = curTime + deltaT;
  newAngularVelocity =
    curAngularVelocity + ((1 - 1/(2 lambda)) alpha[curTime, curAngle, curAngularVelocity] +
      1/(2 lambda) alpha[tStar, thetaStar, omegaStar]) deltaT;
  newAngle = curAngle + (curAngularVelocity + newAngularVelocity) deltaT / 2;
  {newTime, newAngle, newAngularVelocity}
)
```

Displaying The Angle as a Function of Time

Nest the procedure, transpose the results, and produce a plot of the angle θ as a function of time:

```
In[801]:= rk2Results = NestList[rungeKutta2, initialConditions, steps];
rk2ResultsTransposed = Transpose[rk2Results];
times = rk2ResultsTransposed[[1]];
thetas = rk2ResultsTransposed[[2]];
thetaPlot = ListPlot[Transpose[{times, thetas}]];
(* the theoretical solution is approximately known,
provided the angle remains small *)
(* let's plot the envelope of the theoretical solution *)
envelopeFunction[t_] := thetaInitial Exp[-gamma t]
approximateTheoreticalEnvelope =
  Plot[{envelopeFunction[t], -envelopeFunction[t]}, {t, tInitial, tFinal}];
Show[{thetaPlot, approximateTheoreticalEnvelope}]
```

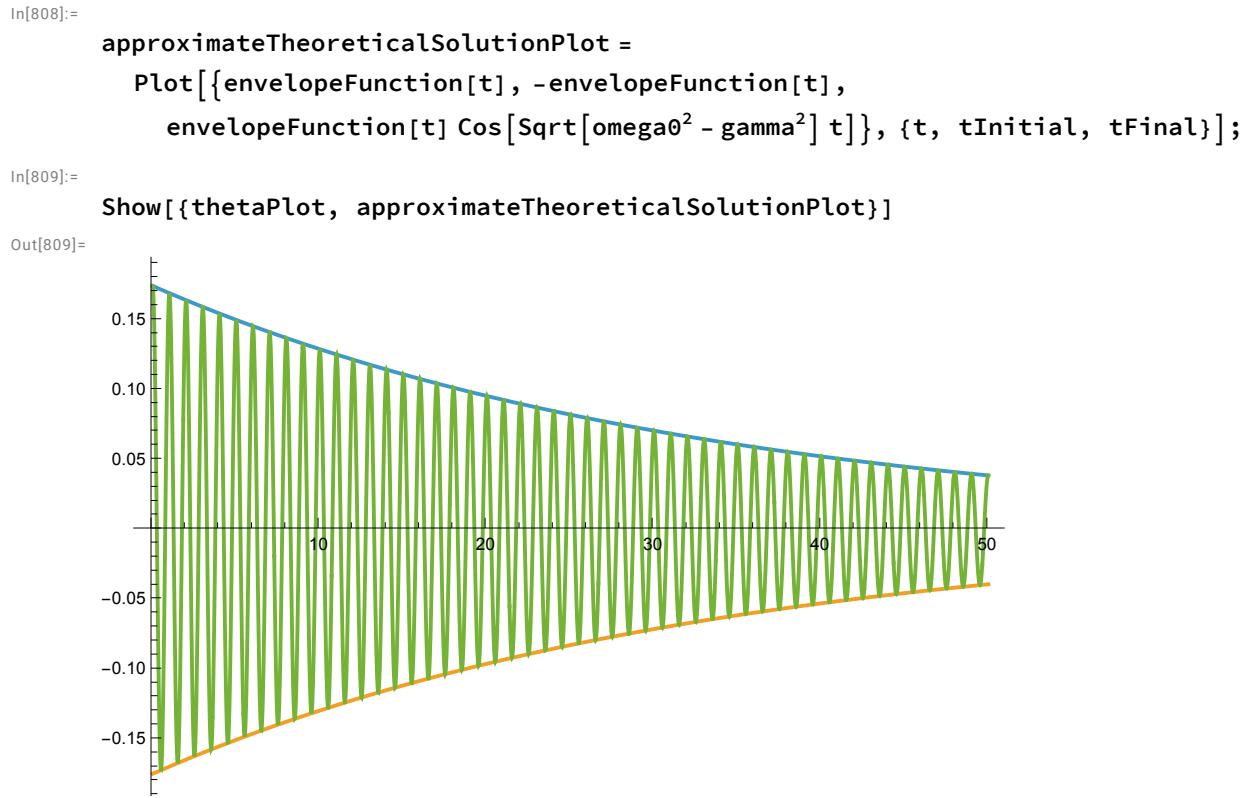
Out[807]=



In the preceding plot, the theoretical solution is approximately known, provided the angle remains small, and so I added the envelope of the theoretical solution to the plot.

Displaying Approximate Theoretical Solution

In the following plot, I have included the theoretical oscillation, not just the envelope (but the same approximation that the angle must remain small still applies):



Drawing a Pendulum with Coordinates and Graphics

To do a legible job of this, you may need to review Section 14 of *EIWL3*.

```
pendulumGraphic[angle_] := Graphics[{
  EdgeForm[Thin], White,
  RegularPolygon[{0.0, 0.0}, 0.4, 4],
  Black,
  Circle[{0, 0}, length],
  Point[{0, 0}],
  Line[{{0, 0}, length {Sin[angle], -Cos[angle]}},
    PointSize[0.03], Purple, (* The PointSize and
    Purple directives affects any remaining items in the list. *)
    Point[length {Sin[angle], -Cos[angle]}]
  ]
}]
```

Animating the Graphics

It's also nice to have an animation, arranged so that the default duration of the animation is the actual duration of the animation:

```
In[811]:= Animate[pendulumGraphic[thetas[[step]]],  
{step, 0, steps, 1}, DefaultDuration → tFinal - tInitial]
```

```
Out[811]=
```

