
Damped Pendulum — With Animated Graphics

Started in class, February 7, 2025, and you are finishing as Problem Set 6 for Feb. 11. Your job is to complete the implementation of the `rungeKutta2[]` function and the `pendulumGraphic[]` function.

This is our sixth numerical methods notebook.

NB: Also due Feb. 11, as Problem Set 7, you are doing the exercises from EIWL3 Sections 18 and 19.

Damped Oscillation

Angular Acceleration α

```
In[194]:= 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[200]:= 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[204]:= thetaInitial = 10 °;
omegaInitial = -gamma thetaInitial;
(* gamma is small, and this is only 0.3° / 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:

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

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

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

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

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

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

We got this by mindlessly making the replacements:

$$x \rightarrow \theta$$

$$v \rightarrow \omega$$

$$a \rightarrow \alpha$$

General Second-Order Runge-Kutta – Implementation

The implementation of the damped pendulum is almost the same as the damped oscillator. Finish the implementation.

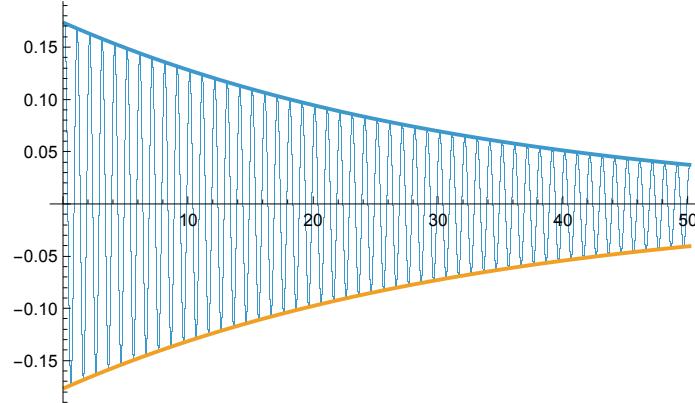
```
In[207]:= lambda = 1;
rungeKutta2[cc_] := (
  (* Extract time, angle, and angular velocity from the list *)
  curTime = cc[[1]];
  curAngle = cc[[2]];
  curAngularVelocity = cc[[3]];
  (* Compute tStar, xStar, vStar *)
  tStar = curTime + lambda deltaT;
  thetaStar = curAngle + curAngularVelocity 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}
)
N[rungeKutta2[initialConditions]]
(* Test the rungeKutta2 function you just wrote. *)
(* The output just below should be {0.0025, 0.174531, -0.00694977} *)
Out[209]= {0.00025, 0.174531, -0.00694977}
```

Displaying Oscillation

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

```
In[210]:= 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[216]=



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.

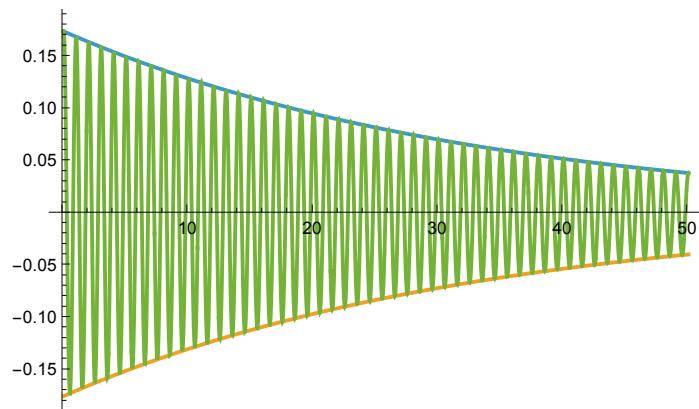
Displaying Theory

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):

```
In[217]:= approximateTheoreticalSolutionPlot =
  Plot[{envelopeFunction[t], -envelopeFunction[t],
    envelopeFunction[t] \times Cos[Sqrt[omega0^2 - gamma^2] t]}, {t, tInitial, tFinal}];
```

```
In[218]:= Show[{thetaPlot, approximateTheoreticalSolutionPlot}]
```

```
Out[218]=
```



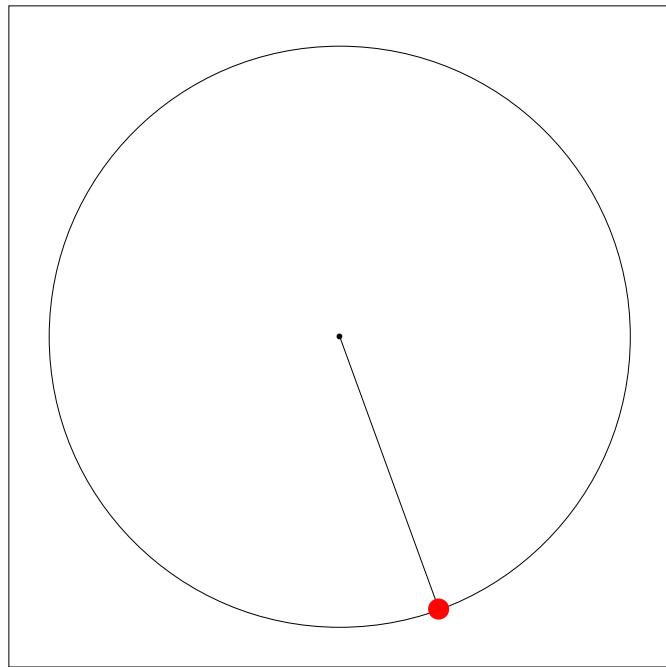
Drawing a Pendulum with Coordinates and Graphics

To do a legible job of this, you may need to review Section 14 of *EIWL3*. The goal is to finish implementing the function below so that you get a picture something like the one I have pasted in.

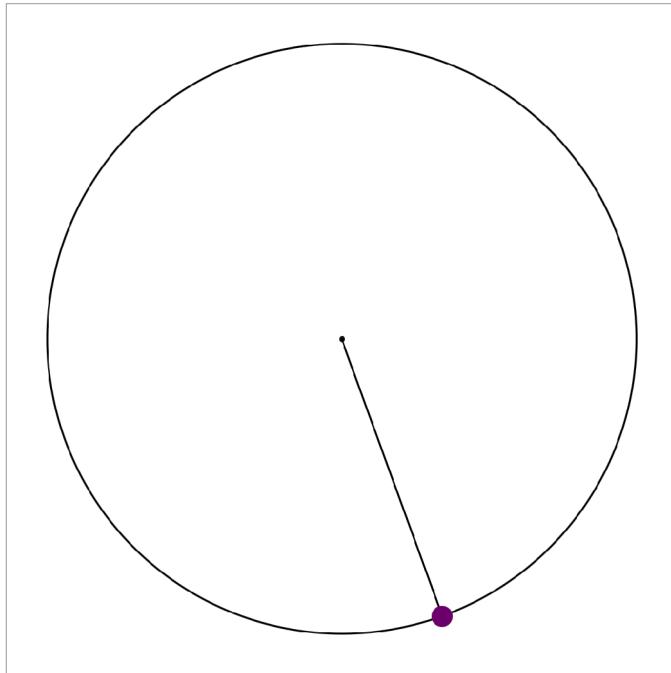
In[219]:=

```
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],  
    Red,  
    Point[length {Sin[angle], -Cos[angle]}]  
    (* all I left for you to add is two points and a line *)  
}]  
pendulumGraphic[20 °]
```

Out[220]=



The pendulum graphic you are trying for (when the function is passed in 20° for the angle, and of course your function should do the right thing for any other 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[221]:=

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

Out[221]=

