

PHYSICS SL

Barton's Pendulum

Session: May 2024

Page Count: 12

Contents

1	Research Question	1
2	Introduction	1
3	Background information	1
3.1	Friction in a pendulum	1
3.2	External periodic force on a pendulum	2
3.3	The Damped, Driven Pendulum	2
4	Hypothesis	3
5	Materials	5
6	Variables	5
6.1	Independent Variable	5
6.2	Dependent Variable	5
6.3	Controlled Variables	5
7	Safety, Ethical, and Environmental Considerations	6
8	Experimental Protocol	6
9	Raw Data	7
9.1	Qualitative Observations	7
9.2	Quantitative Data	7
10	Processed Data	8
11	Analysis	10
12	Evaluation	11
12.1	Strengths	11
12.2	Sources of Error	11
13	Extension	12
	References	12

1 Research Question

What is the relationship between the amplitude of the forced pendulum /rad and the angular frequency of the driver pendulum /rad s⁻¹ in a Barton's pendulum.

2 Introduction

Pendulums undergo a continuous transfer between potential and kinetic energy depending on the position of the pendulum. As a child, I observed this through my myriad number of hours spent on playground swings, where I realized that achieving a greater height necessitated gaining more speed at the bottom. More formally, when I am at a crest in the swing's oscillation, I could reorient my center of mass such that I gain a small increase in my potential energy.

This continuous transfer causes a pendulum system to undergo simple harmonic motion, therefore pendulums have properties such as period and frequency of oscillation defined that are dependent on the length of the pendulum.

What this also means is that any periodic external force will or will not resonate with the pendulum. This applies to various real-life scenarios and problems, from something as little as the frequency that a parent should push their child on a swing to whether gusts of wind are capable of driving an idle wrecking ball to dangerous.

Intuitively, if an external periodic force is resonant with the pendulum, then the extent that the pendulum's amplitude will reach will be at its maximum. However, one should question exactly how this maximum amplitude grows as the frequency of the external force approaches the resonant frequency of the pendulum.

This could easily be investigated by suspending a driving pendulum and a forced pendulum on the same string. This allows for an easy way to provide an external periodic force through the driver pendulum, allowing for the frequency of the external force to be manipulated through changing the length of the driver pendulum and removing the necessity of a motorized instrument.

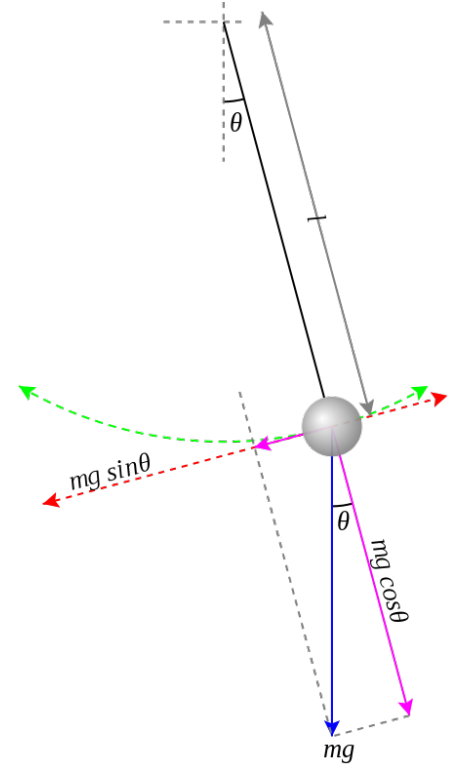


Figure 1: Pendulum labelled with components of gravitational force (Krishnavedala, 25 January 2013, 12:56:47).

3 Background information

3.1 Friction in a pendulum

Because a pendulum is not sliding along a surface, then friction cannot be defined by the formula $F_f = \mu F_N = \mu_d R$. However, a pendulum behaves alike to a particle experiencing frictional force that is proportional to its velocity (*Frictional Force Is Proportional to the Velocity*, 2021). It can therefore be defined as

$$F_f = -\gamma v \quad (1)$$

Where γ = the coefficient of friction of an object experiencing friction through drag /kg s⁻¹

Note that the negative sign is necessary, as the direction of translational velocity of the pendulum opposes the direction of frictional force.

With reference to Figure 1, the displacement along the green arc (s) can be defined below using the definition of a radian.

$$s = l\theta \quad (2)$$

Where l = the length of the forced pendulum /m

Differentiating both sides of Equation 2, the following relationship is obtained.

$$\dot{s} = v = l\dot{\theta} \quad (3)$$

This means that Equation 1 can be rewritten as

$$F_f = -\gamma l\dot{\theta} \quad (4)$$

3.2 External periodic force on a pendulum

The external periodic force on a pendulum can be modelled as follows

$$F_e = A_e \cos(\Omega t) \quad (5)$$

Where F_e = the external periodic force acting on the pendulum /N

A_e = the amplitude of the external periodic force /N

Ω = the angular frequency of the external periodic force /rad s⁻¹

t = duration of time passed after a reference moment in time /s

3.3 The Damped, Driven Pendulum

In Figure 1, the component of gravitational force parallel to the instantaneous velocity of the pendulum is $mg \sin \theta$. However, when letting F_g equal to such component of gravitational force, it must equal to the negative of $mg \sin \theta$ such that the directionality of F_g opposes the directionality of the horizontal component of s .

$$F_g = -mg \sin \theta \quad (6)$$

With reference to Figure 1, Equation 7 can be derived as follows.

$$\begin{aligned} F_{net} &= ma \\ F_g + F_f + F_e &= ma \\ -mg \sin \theta - \gamma l\dot{\theta} + A_e \cos(\Omega t) &= m\ddot{s} \end{aligned} \quad (A)$$

$$\begin{aligned} m\ddot{s} &= -mg \sin \theta \\ l\ddot{\theta} &= -g \sin \theta \end{aligned} \quad (B)$$

$$\begin{aligned} \ddot{\theta} &= -\frac{g}{l} \sin \theta \\ \therefore \omega &= \sqrt{\frac{g}{l}} \\ \ddot{\theta} &= -\omega^2 \sin \theta \end{aligned} \quad (C)$$

Substituting B into A

$$ml\ddot{\theta} - \gamma l\dot{\theta} + A_e \cos(\Omega t) = m\ddot{s} \quad (D)$$

Substituting C into D

$$\begin{aligned} -ml\omega^2 \sin \theta - \gamma l\dot{\theta} + A_e \cos(\Omega t) &= m\ddot{s} \\ \therefore \ddot{s} &= l\ddot{\theta} \end{aligned}$$

$$A_e \cos(\Omega t) = ml\ddot{\theta} + \gamma l\dot{\theta} + ml\omega^2 \sin \theta$$

$$\text{Letting } C = \frac{A_e}{ml}$$

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

$$\ddot{\theta} + \lambda \dot{\theta} + \omega^2 \sin \theta = C \cos(\Omega t) \quad (7)$$

A formula to determine the amplitude of a damped, driven pendulum can be then determined.

Using the small angle approximation of $\sin \theta \approx \theta$

$$\ddot{\theta} + \lambda \dot{\theta} + \omega^2 \theta = C \cos(\Omega t)$$

$$\ddot{z} + \lambda \dot{z} + \omega^2 z = C e^{i\Omega t}$$

The ansatz for z is $A e^{i\Omega t}$ (Chasnov, 2022b)

$$\dot{z} = i\Omega A e^{i\Omega t}, \quad \ddot{z} = -\Omega^2 A e^{i\Omega t}$$

$$-\Omega^2 A + i\lambda\Omega A + \omega^2 A = C$$

$$A = \frac{C}{(\omega^2 - \Omega^2) + i\lambda\Omega} \times \frac{(\omega^2 - \Omega^2) - i\lambda\Omega}{(\omega^2 - \Omega^2) - i\lambda\Omega}$$

$$A = \frac{C [(\omega^2 - \Omega^2) - i\lambda\Omega]}{(\omega^2 - \Omega^2)^2 + \lambda^2\Omega^2}$$

Using the exponential form of complex numbers: $a + bi = r e^{i\phi}$

$$(\omega^2 - \Omega^2) - i\lambda\Omega = e^{i\phi} \sqrt{(\omega^2 - \Omega^2)^2 + \lambda^2\Omega^2}$$

$$A = \frac{C e^{i\phi}}{\sqrt{(\omega^2 - \Omega^2)^2 + \lambda^2\Omega^2}}$$

$$\theta(t) = \Re(A e^{i\Omega t})$$

$$\theta(t) = \Re(e^{i\Omega t} \frac{C e^{i\phi}}{\sqrt{(\omega^2 - \Omega^2)^2 + \lambda^2\Omega^2}})$$

$$\theta(t) = \Re(e^{i(\Omega t + \phi)}) \frac{C}{\sqrt{(\omega^2 - \Omega^2)^2 + \lambda^2\Omega^2}}$$

$$\theta(t) = \left(\frac{C}{\sqrt{(\omega^2 - \Omega^2)^2 + \lambda^2\Omega^2}} \right) \cos(\Omega t + \phi)$$

$$A = \frac{C}{\sqrt{(\omega^2 - \Omega^2)^2 + \lambda^2\Omega^2}} \quad (8)$$

Equation 8 assumes that:

- Due to the small angle approximation made, θ does not exceed 13.99° (“Small-Angle Approximation”, 2023)
- The string connected to the weight is massless

All derivations and ideas within Section 3 were with reference to (Chasnov, 2022b).

4 Hypothesis

When the length of the driver pendulum equals to the length of the forced pendulum, then the amplitude of the forced pendulum will be at its maximum as the two pendulums are in resonance.

As the length of the driver pendulum approaches the length of the forced pendulum, then the amplitude of the forced pendulum will approach that maximum from lower values.

A more detailed hypothesis can be made by referring to and modifying Equation 8.

$$\begin{aligned}
A &= \frac{C}{\sqrt{(\omega^2 - \Omega^2)^2 + \lambda^2 \Omega^2}} \\
A^2 &= \frac{C^2}{(\omega^2 - \Omega^2)^2 + \lambda^2 \Omega^2} \\
A^2 &= \frac{C^2}{\Omega^4 + (\lambda^2 - 2\omega^2)\Omega^2 + \omega^4} \\
\frac{1}{A^2} &= \frac{\Omega^4 + (\lambda^2 - 2\omega^2)\Omega^2 + \omega^4}{C^2} \\
\frac{1}{A^2} &= \frac{1}{C^2}\Omega^4 + \frac{\lambda^2 - 2\omega^2}{C^2}\Omega^2 + \frac{\omega^4}{C^2}
\end{aligned} \tag{9}$$

Unfortunately, Equation 9 cannot be manipulated further to achieve a linearized form. However, that doesn't remove the possibility of analysis despite its form.

If $\frac{1}{A^2}$ is graphed as a function of Ω^2 , a parabola opening upwards should be expected as none of the variables in $C = \frac{A_e}{ml}$ can be negative. Additionally, the question of in which quadrant does the vertex lay can be answered by taking the derivative of Equation 9 with respect to $o = \Omega^2$ and solving for o when the derivative equals to 0.

$$\begin{aligned}
\frac{1}{A^2} &= \frac{1}{C^2}o^2 + \frac{\lambda^2 - 2\omega^2}{C^2}o + \frac{\omega^4}{C^2} \\
\frac{\partial}{\partial o} \left(\frac{1}{A^2} \right) &= \frac{2}{C^2}o + \frac{\lambda^2 - 2\omega^2}{C^2} = 0 \\
o = \Omega^2 &= \omega^2 - \frac{\lambda}{2}
\end{aligned}$$

With reference to Equation 1 that states $F_f = -\gamma v$, it may be assumed that $F_f \ll v$, therefore causing $\lambda = \frac{\gamma}{m}$ to be insignificant. Because both ω and A can only be positive given their contexts, the vertex of $\frac{1}{A^2}$ as a function of Ω^2 must be in the first quadrant.

The specific relationship of A as a function of Ω can be viewed by graphing such a function through Equation 9. This is shown in Figure 2, which the shape of the curve makes sense given that there is a maximum at the resonant angular frequency.

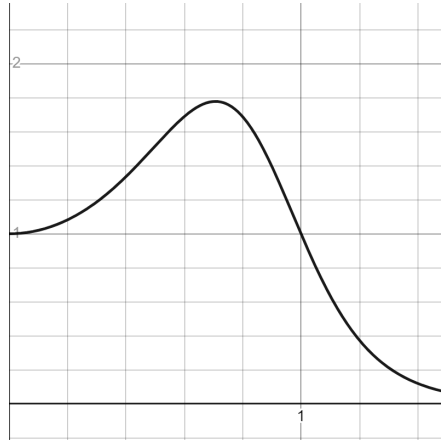


Figure 2: Amplitude of forced pendulum /rad as a function of angular frequency of the driver pendulum /rad s⁻¹ graph using Desmos to present a hypothesis of the function's curve shape

5 Materials

- (3) Retort Stands
- (2) C-clamps
- (4) Clamps
- 11 cm \pm 0.5 cm ruler
- 15 cm \pm 0.5 cm ruler
- (2) Meter Sticks
- (1) 200 g weight
- (1) 50 g weight
- Tape
- String
- Paper
- Scissors
- Highlighter
- Phone Camera

6 Variables

6.1 Independent Variable

The independent variable is the angular frequency of the driver pendulum /rad s⁻¹. In this lab, the independent variable will be changed by shortening the length of the string. This change will be measured by PASCO Capstone's distance measurement tool.

6.2 Dependent Variable

The dependent variable is the amplitude of the forced pendulum /rad. The dependent variable will be measured using PASCO Capstone's object tracking tool.

6.3 Controlled Variables

The first controlled variable will be the starting amplitude of the driver pendulum. This variable will be controlled by setting up a meter stick with its foot pivoted on a retort stand at a consistent position while leaning on the meter stick sitting on top of the clamps between the two primary retort stands, where each trial involved pushing the driver pendulum up to the angle of that leaning meter stick. This variable must be controlled in order to ensure that any changes in the amplitude of the forced pendulum between trials isn't a result of varying initial amplitude of the driver pendulum and therefore inconsistent total energy in the system. This controlled variable is also seen in Equation 8 from $C = \frac{A_e}{ml}$, where A_e is the amplitude of the external periodic force.

The second controlled variable will be the tension in the master string that both pendulums are suspended from. This variable will be controlled by using the same string of a consistent length and maintaining the positions of the primary retort stands with C-clamps. This variable must be controlled to ensure that the degree of energy exchange between the two pendulums is consistent between trials. Additionally, overly loose strings will cause the degree of oscillation in the master string to drastically effect the data.

The third controlled variable is the length of the forced pendulum. This variable will be controlled by not exchanging the string of the forced pendulum between trials. This variable must be controlled to ensure that the angular frequency of the forced pendulum seen in Equation 8 as ω remains consistent. It also ensures that C remains consistent as $C = \frac{A_e}{ml}$, where l is the length of the forced pendulum.

The fourth controlled variable is the mass of the forced pendulum. This variable will be controlled by avoiding the exchange of weights of different masses for the forced pendulum between trials. This variable must be controlled to ensure that the parameters of $C = \frac{A_e}{ml}$ and $\lambda = \frac{\gamma}{m}$ remain consistent.

The fifth controlled variable is the distance between the driver and forced pendulums. Because lower tension will be found at the center of the master string, then a change in distance between the two pendulums will result in reduced/magnified energy transfer between the pendulums.

7 Safety, Ethical, and Environmental Considerations

There were no ethical or environmental issues in this lab. A safety consideration is to avoid excessive tightening of the C-clamp such that the retort stand's base buckles. Another safety consideration is to carry long objects (e.g. meter sticks, retort stands) such that they will not impact delicate objects or others in the lab.

8 Experimental Protocol

A string was cut using scissors to a length that is slightly longer than a meter stick. A good portions of the ends were folded and twisted to create a loop at the ends. Two clamps were positioned near the top of two retort stands where the loops were wrapped around the clamps' screws.

The retort stands were separated as much as possible such that the master string would have as much tension as possible. The retort stands were then secured using the C-clamps. With the bases of the two stands oriented with the rods as far away as possible from each other, the edges of the bases were observed to be 53 cm apart.

The 200 g weight was dedicated to be the driver pendulum and the 50 g weight was dedicated to be the forced pendulum. The motivation of this configuration was that if the driver pendulum had significantly more mass to it, then it would be resistant to complete energy transfers to the forced pendulum.

A slip of paper was coloured with pink highlighter and was wrapped around the 50 g weight. The purpose of doing this was so PASCO Capstone can easily track the forced pendulum.

A string of some arbitrary length was cut and was attached to the forced pendulum and suspended from the master using loops. A triangular ruler was then taped onto the third retort stand, in which the height of the triangular ruler was 11 cm. Using 2 clamps to secure the phone onto one of the primary retort stands, the forced pendulum and the third retort stand were aligned in the same plane, and a picture was taken using the phone. The motivation of this was to analyze that image using PASCO Capstone to determine a more accurate length that considers the center of mass of the weight.

A longer string length was then attached to the 200 g weight for the driving pendulum and suspended on the master string. The forced pendulum was shifted along the master string towards the side of the retort stand with the phone, and the driver pendulum was suspended on the side of the other retort stand. The third retort stand was aligned along the plane of the driver pendulum. A meter stick was placed on top of the two clamps securing the master string and another meter stick was set to lean against the first meter stick with its foot sitting against the base of the third retort stand. The motivation of this set up was to maintain a consistent initial amplitude of the driver pendulum, therefore a 15 cm ruler sat between the two retort stands to ensure that the distance between the two bases are consistent.

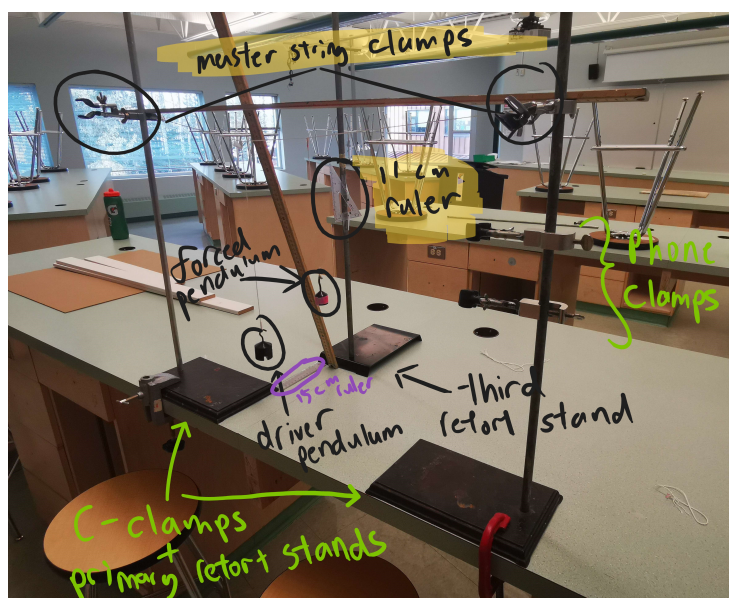


Figure 3: Lab experiment apparatus setup

Each trial involved setting the phone to record the motion of the forced pendulum after releasing the driver pendulum. Changing the driver pendulum's length involved increasing the size of the loop such that the overall length is reduced. If the length reaches the point where there is too much excess string, then some string was cut off to allow this process to continue.

9 Raw Data

9.1 Qualitative Observations

- As the angular frequency of the driver pendulum approached the resonant angular frequency of the forced pendulum, the driver pendulum experiences progressively more complete energy transfers. This was observed as temporary absence of potential and kinetic energy in the driver pendulum when the forced pendulum experiences oscillations of maximum amplitude.
- As the angular frequency of the driver pendulum approached the resonant angular frequency of the forced pendulum, the period that the forced pendulum transitions from no energy to maximum energy back to no energy increased.
- Despite the method of controlling the tension of the master string by avoiding exchange between different master strings, the string was observed to lose tension overtime.
- When the length of the driver pendulum was 0.156 m, the master string failed and collapsed.

9.2 Quantitative Data

Table 1 presents the raw data from a selection of trials, where the values are necessary to determine the angular frequency of the driver pendulum and the maximum amplitude of the forced pendulum for each trial.

Table 1: Average, maximum, and minimum horizontal oscillation position and maximum and minimum vertical oscillation position as functions of the length of driver pendulum

Length of driver pendulum /m	Average of horizontal oscillation position /mm	Maximum of horizontal oscillation position /mm	Minimum of horizontal oscillation position /mm	Maximum of vertical oscillation position /mm	Minimum of vertical oscillation position /mm
0.374 ± 0.007	-2.24 ± 0.04	39.5 ± 0.7	-45.0 ± 0.8	2.50 ± 0.05	-7.9 ± 0.1
0.353 ± 0.006	-15.1 ± 0.3	39.7 ± 0.7	-67 ± 1	4.62 ± 0.08	-4.32 ± 0.08
0.320 ± 0.006	-10.2 ± 0.2	62 ± 1	-86 ± 2	2.50 ± 0.05	-7.9 ± 0.1
0.297 ± 0.005	-13.2 ± 0.2	70 ± 1	-95 ± 2	7.2 ± 0.1	-7.7 ± 0.1
0.269 ± 0.005	-14.1 ± 0.3	104 ± 2	-129 ± 2	17.6 ± 0.3	-6.6 ± 0.1
0.250 ± 0.005	-12.9 ± 0.2	134 ± 2	-157 ± 3	26.1 ± 0.5	-9.1 ± 0.2
0.240 ± 0.004	-13.7 ± 0.2	177 ± 3	-204 ± 4	51.6 ± 0.9	-6.6 ± 0.1
0.229 ± 0.004	-13.8 ± 0.3	205 ± 4	-229 ± 4	75 ± 1	-9.3 ± 0.2
0.203 ± 0.004	-13.1 ± 0.2	193 ± 4	-211 ± 4	63 ± 1	-9.1 ± 0.2
0.168 ± 0.003	-15.0 ± 0.3	114 ± 2	-138 ± 3	25.1 ± 0.5	-9.6 ± 0.2
0.156 ± 0.003	-18.0 ± 0.3	91 ± 2	-129 ± 2	21.9 ± 0.4	-7.3 ± 0.1
0.153 ± 0.003	-18.6 ± 0.3	88 ± 2	-122 ± 2	20.6 ± 0.4	-7.7 ± 0.1
0.130 ± 0.002	-10.8 ± 0.2	69 ± 1	-90 ± 2	13.3 ± 0.2	-6.6 ± 0.1
0.212 ± 0.004	8.0 ± 0.1	197 ± 4	-233 ± 4	74 ± 1	-7.7 ± 0.1
0.115 ± 0.002	-17.9 ± 0.3	57 ± 1	-88 ± 2	10.7 ± 0.2	-7.6 ± 0.1

The uncertainty for each value was dependent on the uncertainty of the ruler used for PASCO Capstone to use as a reference length. Because the calibration of the ruler relied on orienting points based off of pixels,

the confidence and uncertainty of one position along the ruler is the increment of length for each tick on the ruler (± 1 mm). However, because the overall calibration of the ruler's length involves two points, then the final uncertainty for the 11.0 cm ruler is ± 0.2 cm.

Because this uncertainty is relative to the 11.0 cm ruler, then the uncertainties for the distance measurements according to PASCO Capstone will be the percent uncertainty of the ruler. A sample calculation is shown below for the length of the driver pendulum of the first trial.

$$\begin{aligned}
 \text{Let } l_e &= \text{the length of the external driver pendulum /m} \\
 l_r &= \text{the length of the reference ruler /cm} \\
 \Delta l_e &= l_e \left(\frac{\Delta l_r}{l_r} \right) \\
 &= (0.374 \text{ m}) \left(\frac{0.2 \text{ cm}}{11.0 \text{ cm}} \right) \\
 &= 0.007 \text{ m}
 \end{aligned}$$

10 Processed Data

The lengths of the driver pendulums will be used to determine the angular frequency of the driver pendulum for each trial. A sample calculation is shown below for the length of the driver pendulum of the first trial.

From (Gonzales, 2022)

$$\begin{aligned}
 \Omega &= \sqrt{\frac{g}{l_e}} \\
 &= \sqrt{\frac{9.81 \text{ m s}^{-2}}{0.374 \text{ m} \pm 0.007 \text{ m}}} \\
 &= 5.12 \text{ rad s}^{-1} \pm 0.05 \text{ rad s}^{-1}
 \end{aligned}$$

$$\begin{aligned}
 \Delta \Omega &= \Omega \left(\frac{1}{2} \cdot \frac{\Delta l_e}{l_e} \right) \\
 &= (5.12 \text{ rad s}^{-1}) \left(\frac{1}{2} \cdot \frac{0.007 \text{ m}}{0.374 \text{ m}} \right) \\
 &= 0.05 \text{ rad s}^{-1}
 \end{aligned}$$

Next, based on the maximum, minimum, and average positions of the pendulum along the horizontal and vertical axis can be used to determine the pendulum's maximum horizontal and vertical displacement from equilibrium. For the horizontal axis, its maximum distance from equilibrium is the greater value between $|X_{max} - X_{average}|$ and $|X_{min} - X_{average}|$. For the vertical axis, its maximum distance from equilibrium is $|Y_{max} - Y_{min}|$.

The amplitude of the forced pendulum /rad can be determined by taking the maximum horizontal oscillation amplitude and the maximum vertical oscillation amplitude and using cosine law to determine the angle that the forced pendulum has rotated about its pivot. The calculation for this for the first trial is shown below with reference to Figure 4.

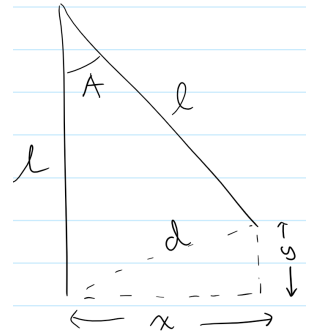


Figure 4: Forced pendulum at its maximum amplitude labelled with relevant variables to determine the value of the maximum amplitude

$$\begin{aligned}
 \text{Let } l &= \text{the length of the forced pendulum} \\
 d^2 &= 2l^2 - 2l^2 \cos A, \quad d^2 = x^2 + y^2 \\
 A &= \arccos \left(1 - \frac{x^2 + y^2}{2l^2} \right) \\
 &= \arccos \left(1 - \frac{(4.27 \text{ cm} \pm 0.09 \text{ cm})^2 + (1.04 \text{ cm} \pm 0.02 \text{ cm})^2}{2(26.1 \text{ cm} \pm 0.5 \text{ cm})^2} \right) \\
 &= 0.168 \text{ rad}
 \end{aligned}$$

Using Equation 10 to propagate the uncertainty
 $A = 0.168 \text{ rad} \pm 0.006 \text{ rad}$

From (*Uncertainties and Error Propagation*, n.d.)

$$\Delta f(a_1, a_2, a_3, \dots) = \sum \left| \frac{\partial f}{\partial a_n} \right| \Delta a_n \quad (10)$$

Where f = the multivariable function whose uncertainty is to be found

a_n = the nth variable in f

Table 2 presents the processed data that will provide the necessary values to graph the relationship between the forced pendulum's maximum amplitude and the angular frequency of the driver pendulum.

Table 2: Maximum horizontal and vertical displacement from equilibrium of forced pendulum and maximum amplitude of forced pendulum as a function of the angular frequency of the driver pendulum

Angular frequency of driver pendulum /rad s ⁻¹	Forced pendulum's maximum horizontal displacement from equilibrium /cm	Forced pendulum's maximum vertical displacement from equilibrium /cm	Forced pendulum's maximum amplitude /rad
5.12 ± 0.05	4.27 ± 0.09	1.04 ± 0.02	0.168 ± 0.006
5.27 ± 0.05	5.5 ± 0.1	0.89 ± 0.02	0.213 ± 0.008
5.54 ± 0.05	7.6 ± 0.2	1.04 ± 0.02	0.30 ± 0.01
5.75 ± 0.05	8.3 ± 0.2	1.49 ± 0.03	0.33 ± 0.01
6.04 ± 0.05	11.9 ± 0.2	2.42 ± 0.04	0.47 ± 0.02
6.26 ± 0.06	14.6 ± 0.3	3.51 ± 0.06	0.58 ± 0.02
6.39 ± 0.06	19.1 ± 0.3	5.8 ± 0.1	0.78 ± 0.03
6.55 ± 0.06	21.9 ± 0.4	8.5 ± 0.2	0.93 ± 0.04
6.96 ± 0.06	20.6 ± 0.4	7.2 ± 0.1	0.86 ± 0.03
7.64 ± 0.07	12.9 ± 0.2	3.48 ± 0.06	0.52 ± 0.02
7.93 ± 0.07	11.1 ± 0.3	2.92 ± 0.05	0.44 ± 0.02
8.00 ± 0.07	10.7 ± 0.2	2.83 ± 0.05	0.43 ± 0.02
8.69 ± 0.08	8.0 ± 0.1	1.99 ± 0.04	0.32 ± 0.01
6.80 ± 0.06	24.1 ± 0.4	8.1 ± 0.1	1.02 ± 0.04
9.24 ± 0.08	7.5 ± 0.1	1.83 ± 0.03	0.29 ± 0.01

Table 3 presents the reciprocal of the forced pendulum's maximum amplitude squared as a function of the square of the angular frequency of the driver pendulum. Note that Equation 10 was used to propagate the uncertainties of the values in the table.

Table 3: Reciprocal of the forced pendulum's maximum amplitude squared as a function of the square of the angular frequency of the driver pendulum

Square of angular frequency of driver pendulum $/\text{rad}^2 \text{s}^{-2}$	Reciprocal of the forced pendulum's maximum amplitude squared $/\text{rad}^{-2}$
26.24 ± 0.09	35 ± 3
27.8 ± 0.1	22 ± 2
30.7 ± 0.1	11 ± 1
33.0 ± 0.1	9.5 ± 0.7
36.4 ± 0.1	4.6 ± 0.3
39.2 ± 0.1	2.9 ± 0.2
40.8 ± 0.1	1.6 ± 0.1
42.9 ± 0.1	1.16 ± 0.09
48.4 ± 0.1	1.3 ± 0.1
58.4 ± 0.1	3.8 ± 0.3
62.9 ± 0.1	5.1 ± 0.4
64.0 ± 0.1	5.5 ± 0.4
75.6 ± 0.2	10.1 ± 0.7
46.2 ± 0.1	0.97 ± 0.08
85.3 ± 0.2	11.5 ± 0.8

11 Analysis

As seen in Figure 5, a portion of the hypothesis has been proven, where there is a maximum in the graph at when the driver pendulum's angular frequency resonates with the forced pendulum's angular frequency.

The trend in Figure 6 does not fit the parabolic model discussed earlier. However, further inspection may suggest that the first portion follows a trend resembling one that is quadratic, with the final 5 data points breaking the trend. By restricting the data points to not include the final 5 values, a graph is produced that better fits the parabolic model, as seen in Figure 7.

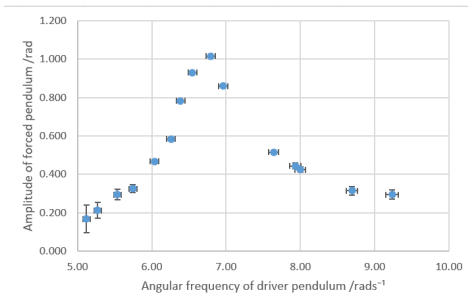


Figure 5: Amplitude of forced pendulum $/\text{rad}$ as a function of angular frequency of driver pendulum $/\text{rad s}^{-1}$ to confirm the hypothesis to the research question

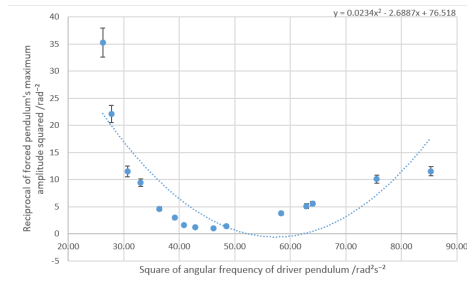


Figure 6: Reciprocal of forced pendulum's maximum amplitude squared $/\text{rad}^{-2}$ as a function of square of angular frequency of driver pendulum $/\text{rad}^2 \text{s}^{-2}$ to indicate error in data

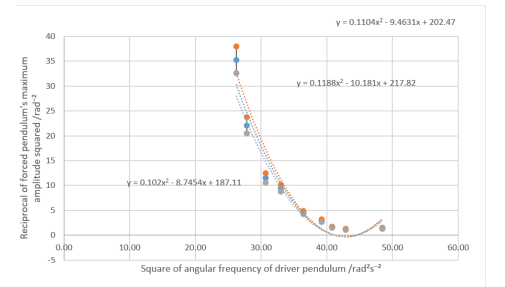


Figure 7: Reciprocal of forced pendulum's maximum amplitude squared $/\text{rad}^{-2}$ as a function of square of angular frequency of driver pendulum $/\text{rad}^2 \text{s}^{-2}$ to focus on the portion of the data that best follows the parabolic model

The parameters of the best-fit parabola can be used in conjunction with Equation 8 to quantify the data's accuracy. Specifically, the parameters can be used to experimentally determine the forced pendulum's angular frequency, which is comparable to a theoretical value obtained by $\omega = \sqrt{\frac{g}{l}}$.

The following parabolic relationship is formed from the topmost trend and lowest trend maximized and

minimized respectively according to y-intercept which is the most significant parameter to determining the experimental angular frequency of the forced pendulum.

$$\frac{1}{A^2} = (0.110 \text{ s}^4 \pm 0.008 \text{ s}^4)\Omega^4 - (9.5 \text{ rad}^2 \text{ s}^{-2} \pm 0.7 \text{ rad}^2 \text{ s}^{-2})\Omega^2 + (2.0 \times 10^2 \text{ rad}^4 \pm 0.2 \times 10^2 \text{ rad}^4) \quad (11)$$

The experimental and theoretical angular frequencies of the forced pendulum can be determined as shown below.

$$\begin{aligned} \frac{1}{C^2} &= 0.110 \text{ s}^4 \pm 0.008 \text{ s}^4, \quad \frac{\omega^4}{C^2} = 2.0 \times 10^2 \text{ rad}^4 \pm 0.2 \times 10^2 \text{ rad}^4 \\ \omega^4 \left(\frac{1}{C^2} \right) &= 2.0 \times 10^2 \text{ rad}^4 \pm 0.2 \times 10^2 \text{ rad}^4 \\ \omega^4(0.110 \text{ s}^4 \pm 0.008 \text{ s}^4) &= 2.0 \times 10^2 \text{ rad}^4 \pm 0.2 \times 10^2 \text{ rad}^4 \\ \omega &= 6.5 \text{ rad s}^{-1} \pm 0.3 \text{ rad s}^{-1} \end{aligned}$$

$$\begin{aligned} \omega_{theoretical} &= \sqrt{\frac{g}{l}} \\ &= \sqrt{\frac{9.81 \text{ m s}^{-2}}{0.261 \text{ m} \pm 0.005 \text{ m}}} \\ &= 6.13 \text{ rad s}^{-1} \pm 0.06 \text{ rad s}^{-1} \end{aligned}$$

12 Evaluation

The experimental and theoretical values of the angular frequency of the forced pendulum at a glance look very close; however, the ranges defined by their uncertainties barely intersect (6.2 rad s^{-1} and 6.19 rad s^{-1}). This indicates that the data collected in the experiment isn't the most accurate. This was already evident in Figure 5 where the final 5 data points break the quadratic trend. While one may argue that the holistic trend could be cubic, the theory only backs up the argument that the relationship between $\frac{1}{A^2}$ and Ω^2 is quadratic. Despite this, further investigation is required to confirm the portion of the hypothesis predicting that this relationship is quadratic.

12.1 Strengths

Most experiments investigating an external periodic force applied to a simple harmonic motion system are done by using a motor to provide the external periodic force. However, this experiment does not necessitate the need to design a motor, as the external periodic force is provided by the driver pendulum that can be easily made by anyone.

12.2 Sources of Error

The first source of error was the progressive decrease in master string's tension overtime. Because of the exaggerated amplitude of the forced pendulum due to the additional master string's oscillation and magnified energy transfer between the driver and forced pendulum, then it is expected that data points surrounding the median of the angular frequencies of the driver pendulum will have an amplitude that is higher than reality. This in turn causes the data points in the center of Figure 7 to be lower than reality. Assuming that the first data point in Figure 7 remains static, then if all the other data points were adjusted to be increased, than the y-intercept would be expected to decrease. This in turn would cause the experimental value of ω

to decrease and therefore increase the likelihood that the experimental value matches the theoretical value. The first improvement is to layer the master string with multiple strands such that the master string is less prone to losing its tension. Another improvement is to use a different material for the master string such as fishing line that is less prone to stretch overtime.

The second source of error was the master string's failure when the length of the driver pendulum was 0.156 m. This explains the break in the trend in Figure 5, as this was the 5th last data point that started the break in the trend. The break in the trend was specifically the way in which the 5 last data points fell under the expected curve given by the best-fit parabola of the rest of the data points, and this makes sense given this source of error as because a loosened string that was reattached to the retort stands would allow for more energy transfer between the pendulums and exaggerated oscillations due to the master's string's additional oscillation, then A would become larger than expected, which in turn causes $\frac{1}{A^2}$ to be lower than expected. An improvement to solve this source of error is to layer the master string with multiple strands such that the master string has increased durability to avoid failure.

13 Extension

The master string was the medium that permitted the energy transfer between the driver pendulum and the forced pendulum. In the sources of error, it became evident how loosening the string resulted in greater energy transfer. Thus, an area of extension is to investigate how changing the position of the driver or forced pendulum along the master string influences the maximum amplitude of the forced pendulum.

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