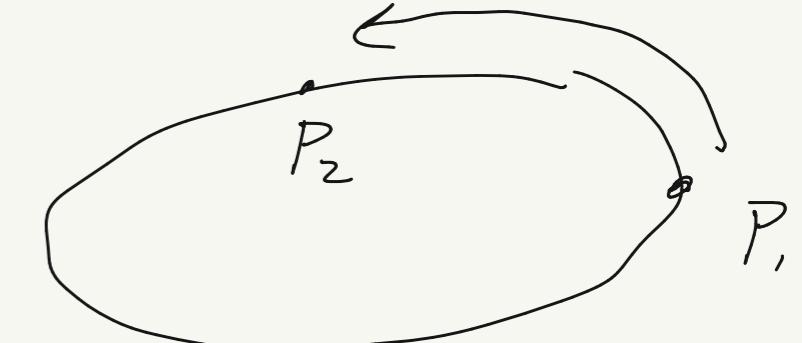


Lecture #1: Aug 24th

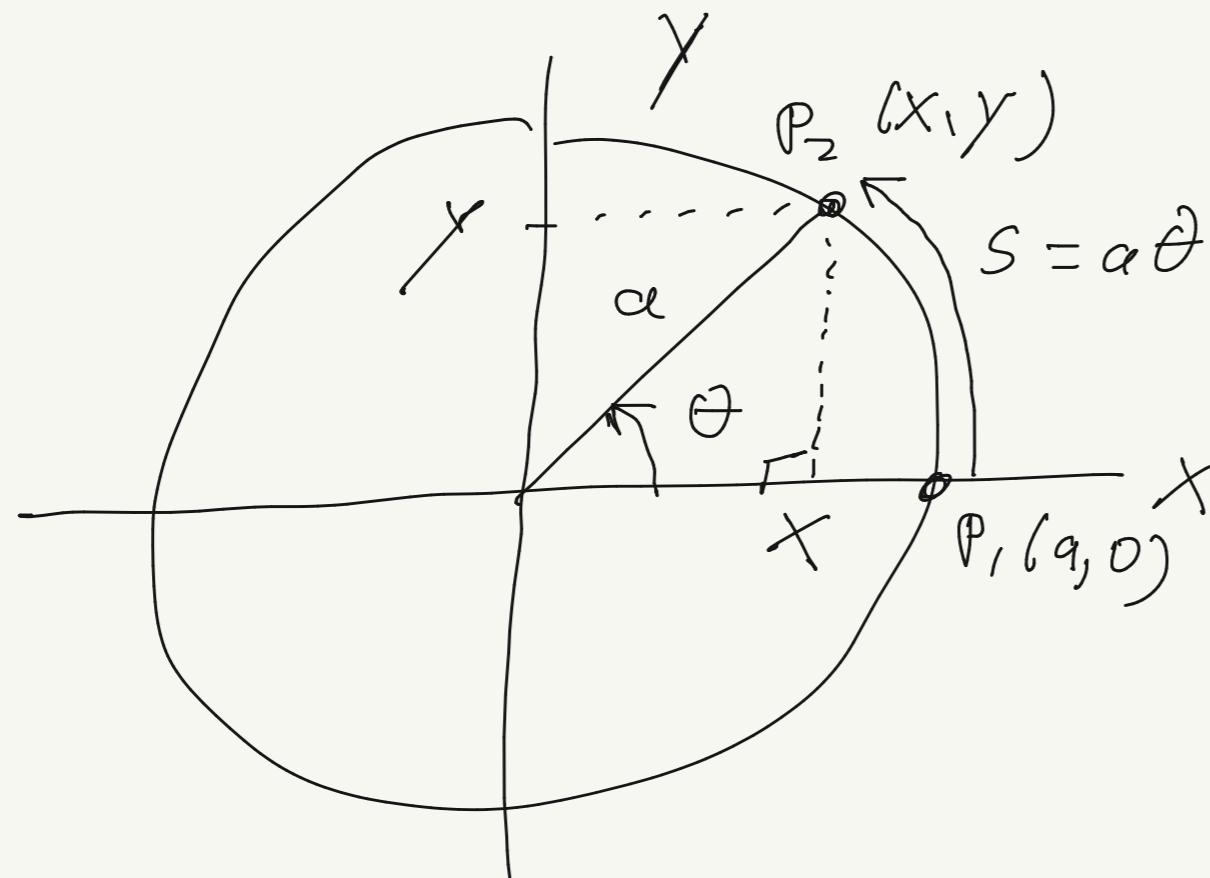
Elliptic functions / integrals:

i) circumference of an ellipse

ii) period of a simple pendulum beyond the small-angle approximation



Circular functions: sines, cosines,



$a = \text{radius}$

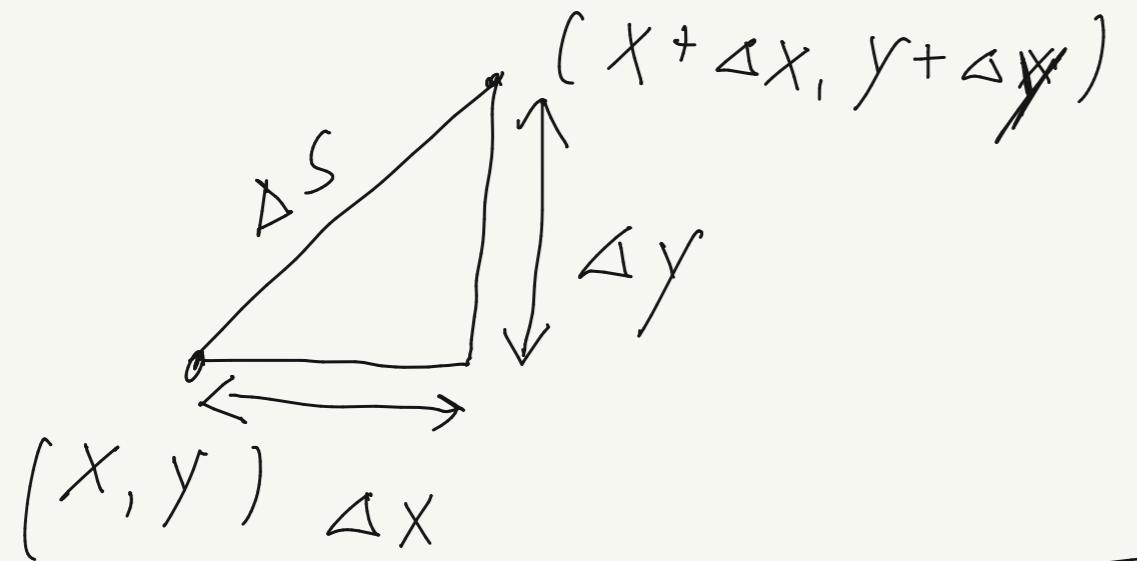
$$x^2 + y^2 = a^2$$

$$\theta = \frac{s}{a}$$

$$= \frac{1}{a} \int \sqrt{dx^2 + dy^2}$$

$$ds^2 = dx^2 + dy^2$$

$$= \int d\theta \Big|_{P_1}^{P_2}$$



$$x = a \cos \theta$$

$$y = a \sin \theta$$

$$\left. \begin{aligned} \sin \theta &= y/a \\ \cos \theta &= x/a \end{aligned} \right\} \text{def. of } \sin \theta, \cos \theta$$

$$\boxed{x^2 + y^2 = a^2} \rightarrow \boxed{\cancel{a^2}(\cos^2 \theta + \sin^2 \theta) = a^2}$$

$$\boxed{\cos^2 \theta + \sin^2 \theta = 1}$$

$$\boxed{\frac{d}{d\theta} \sin \theta = \cos \theta}$$

Proof:

$$\begin{aligned} \frac{d}{d\theta} \sin \theta &= \frac{d}{d\theta} \left(\frac{y}{a} \right) \\ &= \frac{1}{a} \frac{dy}{d\theta} \\ &= \frac{dy}{\sqrt{dx^2 + dy^2}} \\ &= \frac{1}{\sqrt{dx^2 + dy^2}} \quad \stackrel{?}{=} \quad \sqrt{\left(\frac{dx}{dy} \right)^2 + 1} \end{aligned}$$

A diagram showing a point on a curve with a small displacement vector $d\theta = ds$.

$$d\theta = \sqrt{dx^2 + dy^2}$$

$$x^2 + y^2 = a^2 \rightarrow 2x dx + 2y dy = 0$$

$$\frac{dx}{dy} = -\frac{y}{x}$$

$$\frac{d}{d\theta} \sin \theta = \frac{1}{\sqrt{\left(\frac{y}{x}\right)^2 + 1}} = \frac{1}{\sqrt{\frac{x^2}{x^2} + 1}} = \frac{x}{\sqrt{x^2 + y^2}} = \frac{x}{a} = \cos \theta$$

$$\boxed{\frac{d}{d\theta} \sin \theta = \cos \theta}$$

Similarly

$$\boxed{\frac{d \cos \theta}{d \theta} = -\sin \theta}$$

$$\int \frac{d(\sin \theta)}{\cos \theta} = \int d\theta = \theta + \text{const}$$

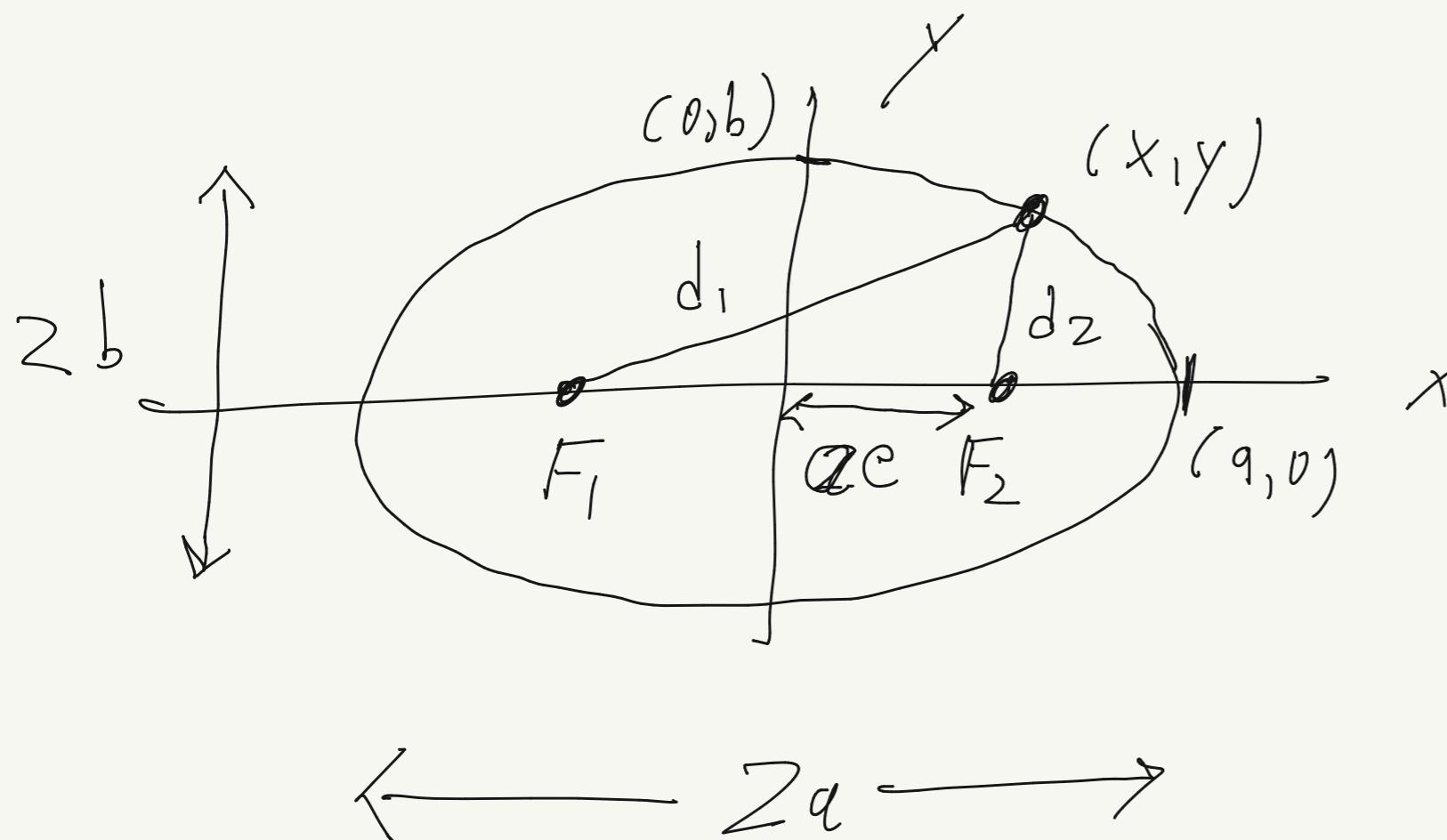
$$t = \sin \theta$$

$$\cos \theta = \sqrt{1 - \sin^2 \theta} = \sqrt{1 - t^2}$$

$$\int \frac{dt}{\sqrt{1-t^2}} = \theta + \text{const}$$

$$\boxed{\sin^{-1} t + \text{const}}$$

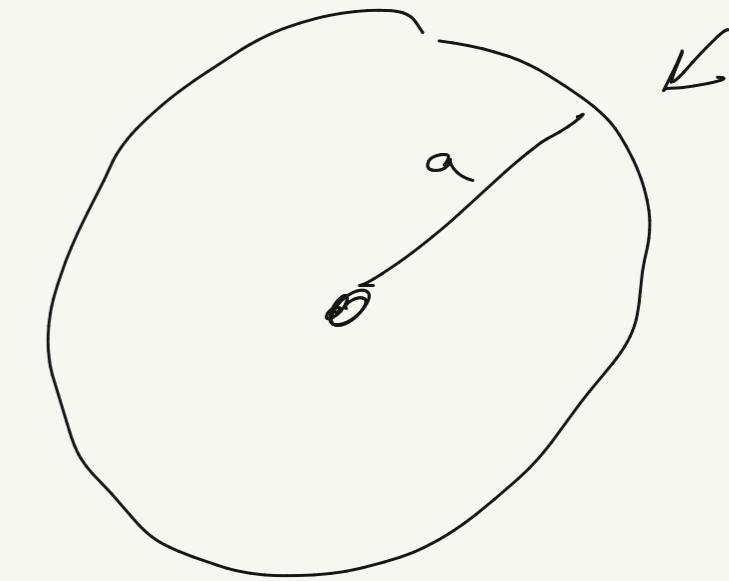
Lec #2 : Aug 26th



$$d_1 + d_2 = 2a$$

$$x^2 + y^2 = a^2$$

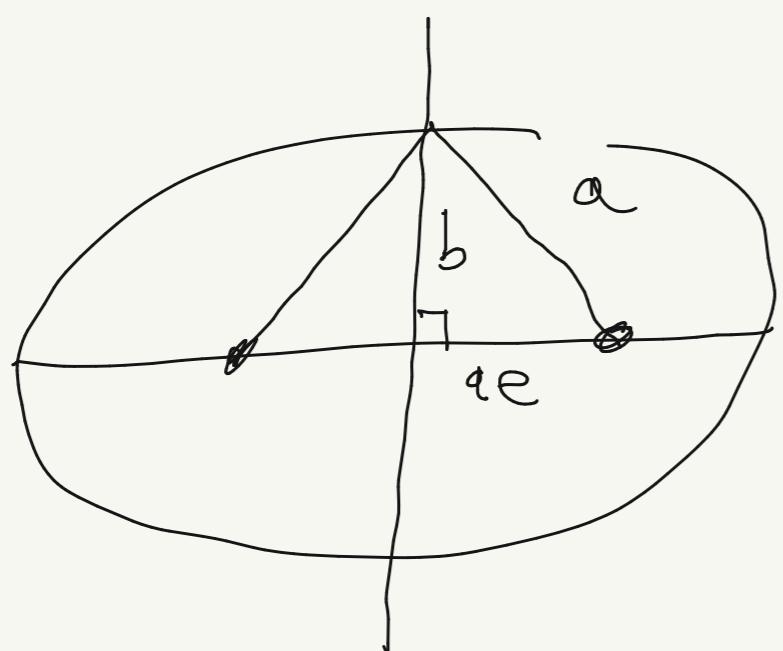
$$e \neq \frac{b}{a}$$



$$e \neq 1 - \frac{b}{a}$$

$$e^2 = \frac{b^2}{1-a^2}$$

$$e = \sqrt{1 - \left(\frac{b}{a}\right)^2}$$

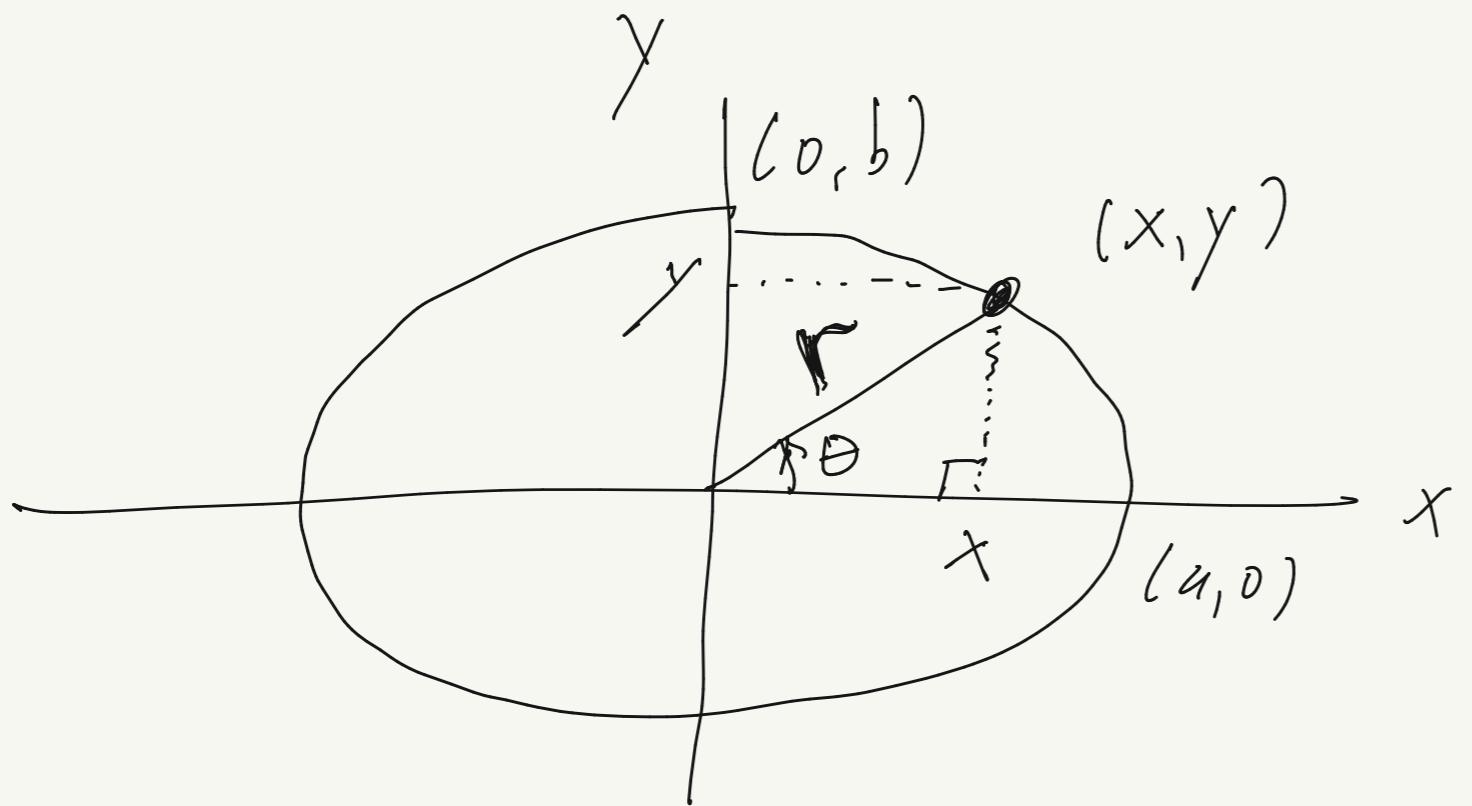


$$PF: a^2 = b^2 + (a\alpha_e)^2$$

$$a^2(1-e^2) = b^2$$

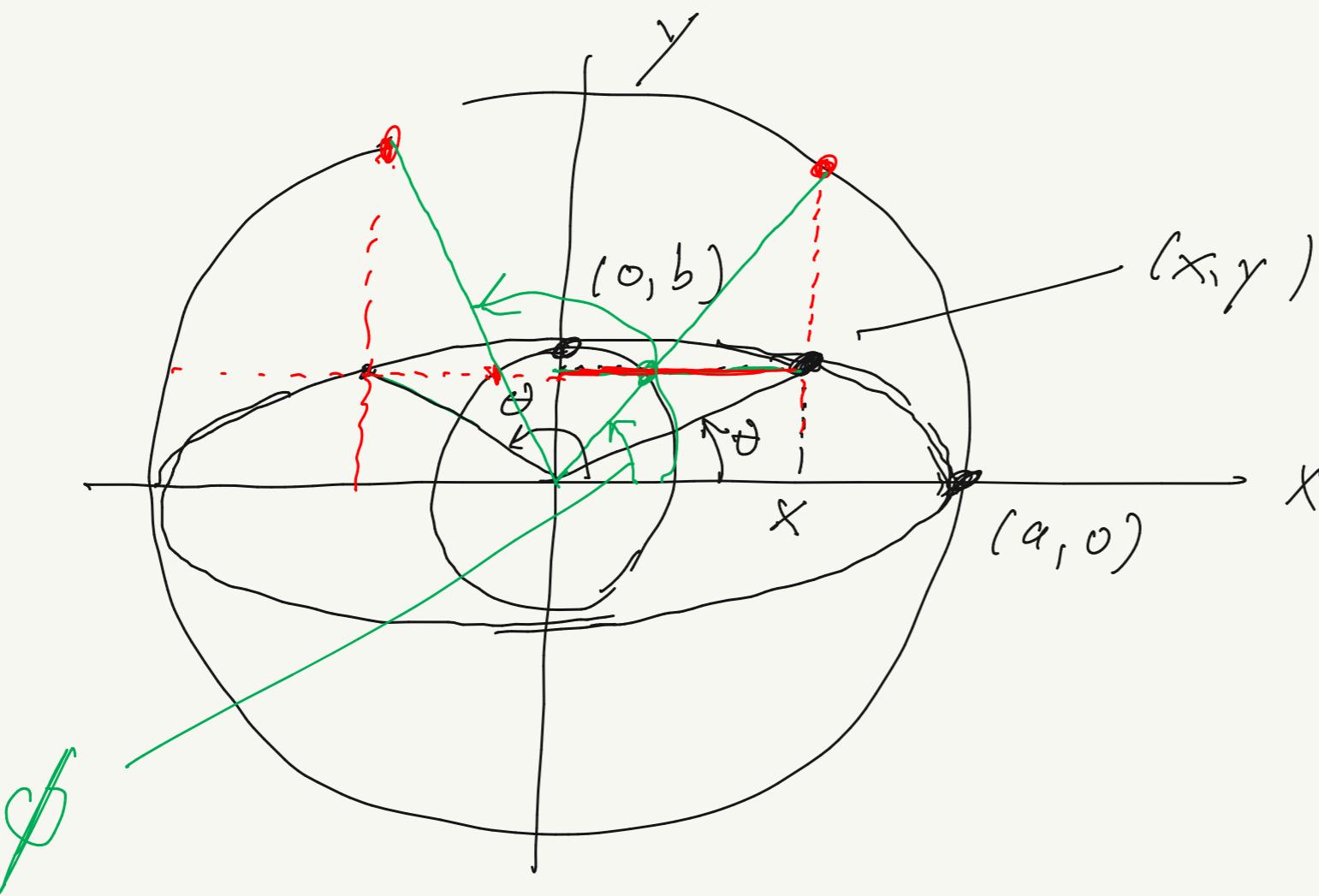
$$1-e^2 = \left(\frac{b}{a}\right)^2$$

$$e = \sqrt{1 - \left(\frac{b}{a}\right)^2}$$



$$\left(\frac{x}{a}\right)^2 + \left(\frac{y}{b}\right)^2 = 1 \quad \leftarrow$$

$$\begin{cases} x = a \cos \phi \\ y = b \sin \phi \end{cases}$$



$$\begin{aligned} x &= r \cos \theta \\ y &= r \sin \theta \\ r &\text{ changes} \end{aligned}$$

$$0 < e < 1$$

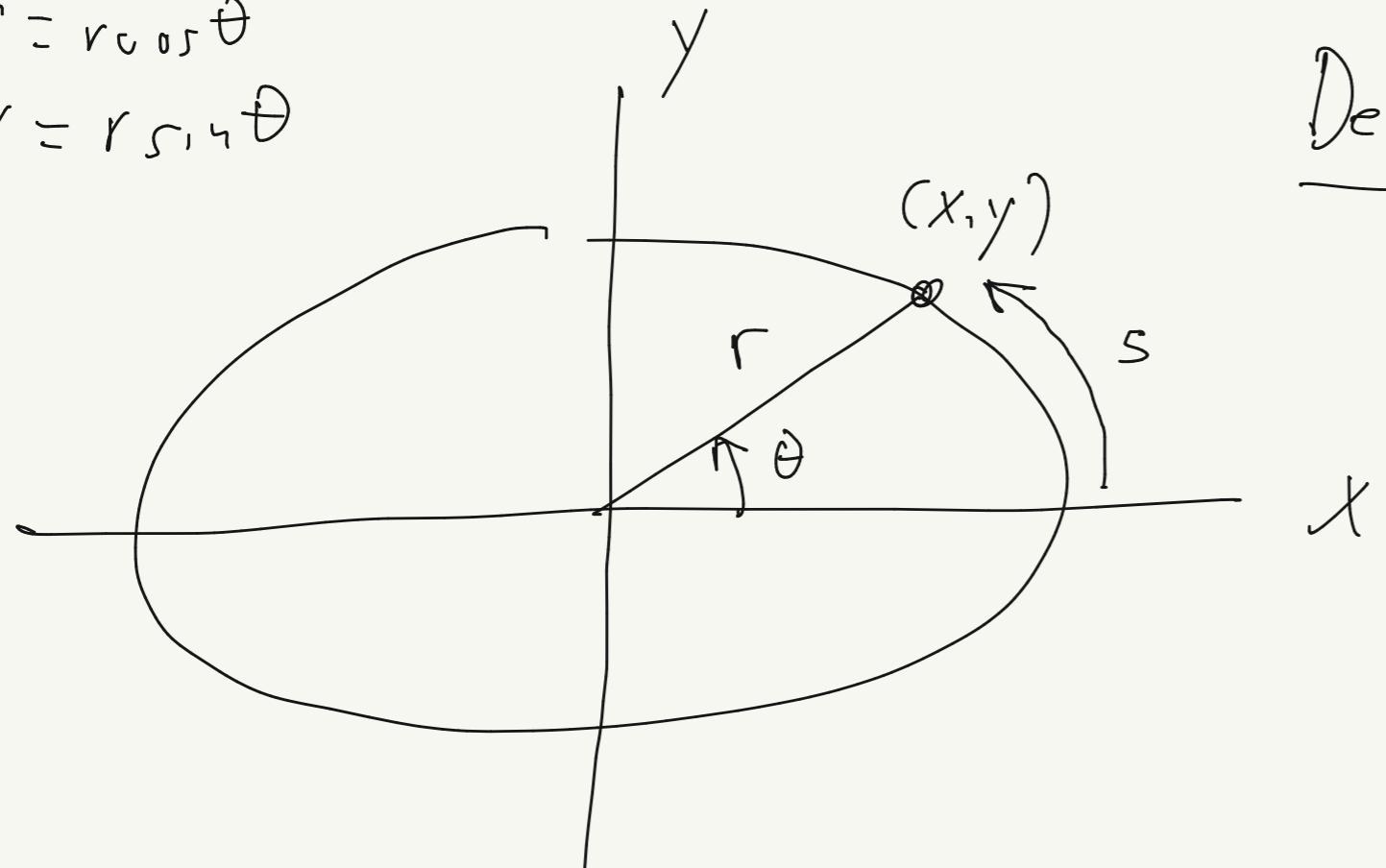
$e = 0$ circle

$e \approx 1$ parabola

$e > 1$ hyperbola

$$x = r \cos \theta$$

$$y = r \sin \theta$$



Defn:

$$\begin{cases} \operatorname{cn}(u; k) = x/a \\ \operatorname{sn}(u; k) = y/b \\ \operatorname{dn}(u; k) = s/a \end{cases}$$

$$k = e, \quad 0 < k < 1$$

modulus

$$\begin{aligned} ds &= \sqrt{dx^2 + dy^2} \\ &= \sqrt{dr^2 + r^2 d\theta^2} \end{aligned}$$

$$\int u = \int_0^\theta r d\theta < s$$

$$u \equiv \frac{1}{b} \int_0^\theta r d\theta$$

↑
not θ , not arc length

$$\begin{aligned} x &= r \cos \theta, \quad y = r \sin \theta \\ dx &= dr \cos \theta - r \sin \theta d\theta \\ dy &= dr \sin \theta + r \cos \theta d\theta \end{aligned}$$

$\operatorname{cn}(u)$ $\operatorname{sn}(u)$	pendulum $k = \sin\left(\frac{\phi_0}{2}\right)$
--	---

Property:

$$\boxed{Cn^2 u + Sn^2 u = 1} \quad \leftarrow \quad \left(\frac{x}{a} \right)^2 + \left(\frac{y}{b} \right)^2 = 1$$
$$\leftarrow \quad x^2 + y^2 = r^2$$

$$\begin{aligned} d n^2 u &= Cn^2 u + \left(\frac{b}{a} \right)^2 Sn^2 u \\ &= 1 - Sn^2 u + \left(\frac{b}{a} \right)^2 Sn^2 u \\ &= 1 - Sn^2 u \left(1 - \left(\frac{b}{a} \right)^2 \right) \\ &= 1 - H^2 Sn^2 u \end{aligned}$$

$$\boxed{d n^2 u + H^2 Sn^2 u = 1}$$

$$\frac{d}{du} \sin u = \frac{1}{b} \frac{dy}{du}$$

$$= \frac{dy}{r d\theta}$$

$$u = \int_0^\theta (r d\theta)$$

$$du = \frac{r d\theta}{b} \rightarrow b du = r d\theta$$



$$x = r \cos \theta, y = r \sin \theta$$

$$\begin{aligned} dx &= dr \cos \theta - r \sin \theta d\theta & \rightarrow \sin \theta dx = \sin \theta \cos \theta dr - r \sin^2 \theta d\theta \\ dy &= dr \sin \theta + r \cos \theta d\theta & \rightarrow -\cos \theta dy = -\cos \theta \sin \theta dr - r \cos^2 \theta d\theta \end{aligned}$$

add

$$\sin \theta dx - \cos \theta dy = -r d\theta$$

$$\frac{y}{r} dx - \frac{x}{r} dy = -r d\theta$$

$$\rightarrow \boxed{rd\theta = \frac{-y}{r} dx + \frac{x}{r} dy}$$

$$\frac{d}{du} \sin u = \frac{dy}{-\frac{y}{r} dx + \frac{x}{r} dy}$$

$$= \frac{r}{-\frac{y}{r} \frac{dx}{dy} + x}$$

$$\left(\frac{x}{a}\right)^2 + \left(\frac{y}{b}\right)^2 = 1 \quad \cancel{\int \frac{x dx}{a^2} + \cancel{\int y dy}}_{\text{= 0}} = 0$$

$$\frac{dx}{dy} = -\frac{y}{x} \frac{a^2}{b^2}$$

$$\frac{d \sin u}{du} = \frac{r}{-y \left(\frac{-y}{x}\right) \frac{a^2}{b^2} + x} = \frac{r}{y^2 \left(\frac{a}{b}\right)^2 + x^2}$$

$$= \frac{r}{a} \frac{x}{a} \left(\frac{1}{\left(\frac{y}{b}\right)^2 + \left(\frac{x}{a}\right)^2} \right)$$

$$= \frac{\sin u \cdot \cos u}{1}$$

$$\boxed{\frac{d}{du} \sin u = \cos u \cdot \frac{d}{du} u}$$

$$\frac{d}{du} \boxed{\operatorname{cn} u} = -\operatorname{sn} u \cdot \operatorname{dn} u$$

$$\frac{d}{du} \operatorname{dn} u = -\pi^2 \operatorname{sn} u \cdot \operatorname{cn} u$$

$$\frac{d}{du} \operatorname{sn} u = \operatorname{cn} u \cdot \operatorname{dn} u$$

$$\operatorname{sn}^2 u + \operatorname{cn}^2 u = 1$$

$$\operatorname{dn}^2 u + \pi^2 \operatorname{sn}^2 u = 1$$

$$\int \frac{d(\operatorname{cn} \theta)}{\operatorname{cos} \theta} = \int d\theta = \theta$$

$$\int \frac{dt}{\sqrt{1-t^2}} = \operatorname{sn}^{-1} t \quad \theta = \operatorname{cn}^{-1} t$$

Integrate!

$$\int \frac{d(\operatorname{sn} u)}{\operatorname{cn} u \cdot \operatorname{dn} u} = \int du = u + \text{const}$$

$$t = \operatorname{sn} u$$

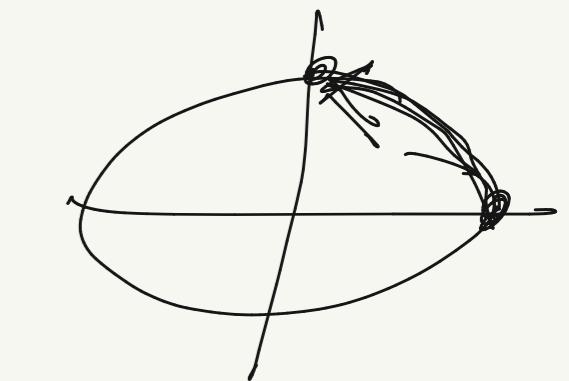
$$\int \frac{dt}{\sqrt{1-t^2} \sqrt{1-\pi^2 t^2}} = \operatorname{sn}^{-1}(t; \pi) + \text{const}$$

$$F(\phi, k) = \int_0^{\sin \phi} \frac{dt}{\sqrt{1-t^2} \sqrt{1-k^2 t^2}}$$

$$\left. \begin{aligned} \sin u &= \sin \phi \\ \frac{y}{b} &= \sin \phi \\ \cnu u &= \cos \phi \end{aligned} \right\}$$

incomplete elliptic integral of 1st kind (angular dependent, period of a simple pendulum)

$$E(\phi, k) = \int_0^{\sin \phi} \frac{dt}{\sqrt{1-t^2} \sqrt{1-k^2 t^2}}$$



incomplete elliptic integral of 2nd kind (arc length along ellipse)

$$\phi = \frac{\pi}{2}$$

$$\int_0^1 \frac{dt}{\sqrt{1-t^2} \sqrt{1-k^2 t^2}} = K(k)$$

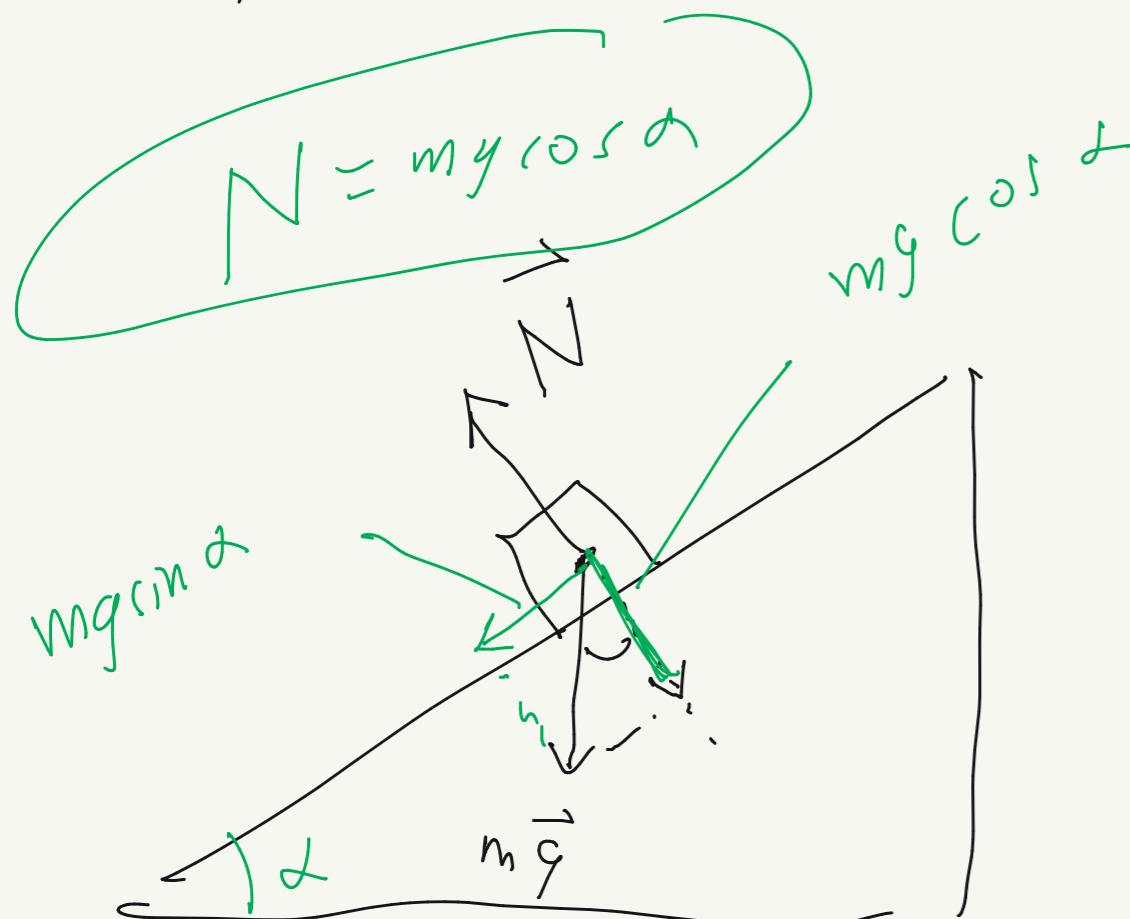
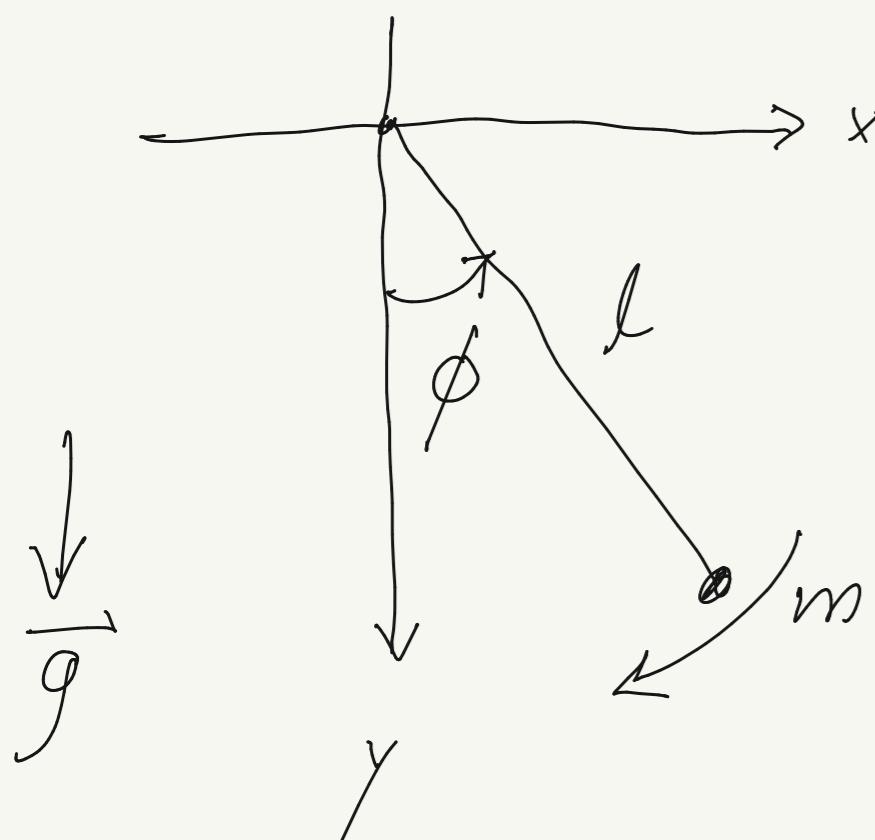
$$\int_0^1 \frac{dt}{\sqrt{1-t^2}} \sqrt{1-k^2 t^2} = E(k)$$

complete elliptic integrals
of 1st and
2nd kind

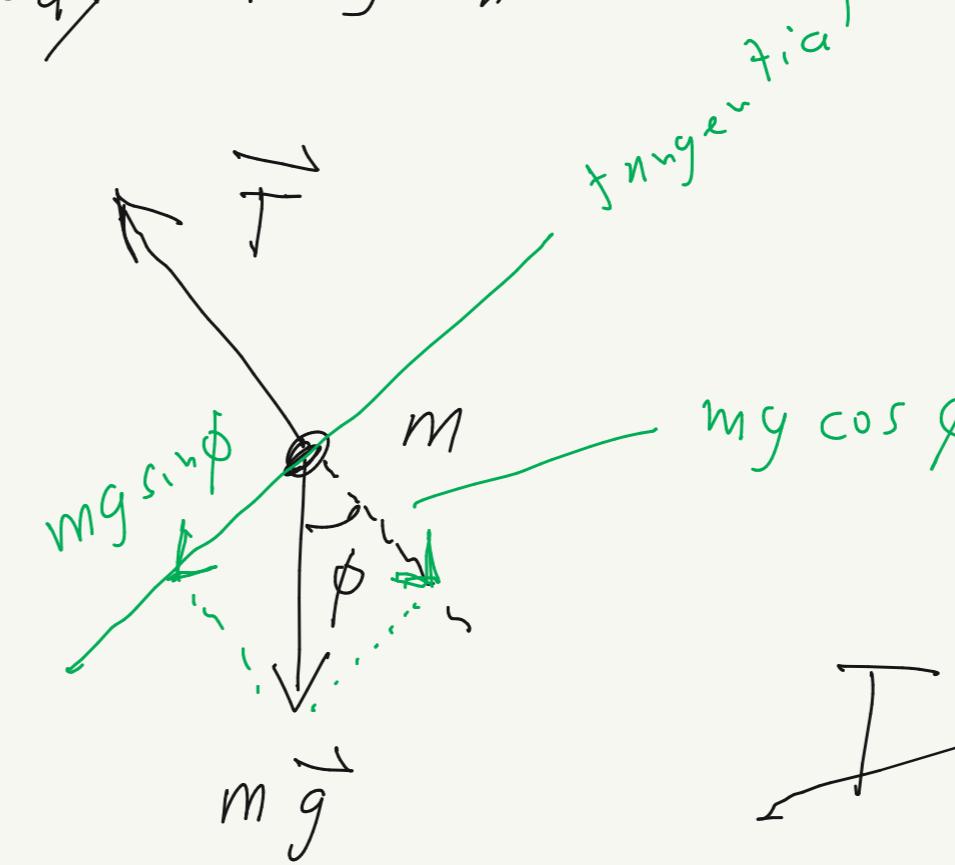
Lec #3: Aug 31st

Simpl. pendulum:

("Freshman physics")



Free-body diagram:



$$1) T - mg \cos \phi = m \dot{\phi}^2 l$$

$$[T = m \dot{\phi}^2 l + mg \cos \phi]$$

$$2) mg \sin \phi = -m \alpha_{\text{tangential}}$$

$$\ddot{\phi} = -\frac{g}{l} \sin \phi$$

EOM

$$a_c = \frac{v^2}{r} = \omega^2 r$$

$$a_t = \alpha r$$

$$\alpha = \ddot{\phi}, \omega = \dot{\phi}$$

$$\ddot{\phi} = -\frac{g}{l} \sin \phi \quad \left(\text{hard to solve; } 2^{\text{nd}} \text{ order non-linear ODE} \right)$$

Small-angle approx: $\phi \ll 1$ rad $\approx 57^\circ$ (π radians = 180°)

$$\rightarrow \ddot{\phi} = -\frac{g}{l} \phi \quad \omega_0 = \sqrt{\frac{g}{l}}$$

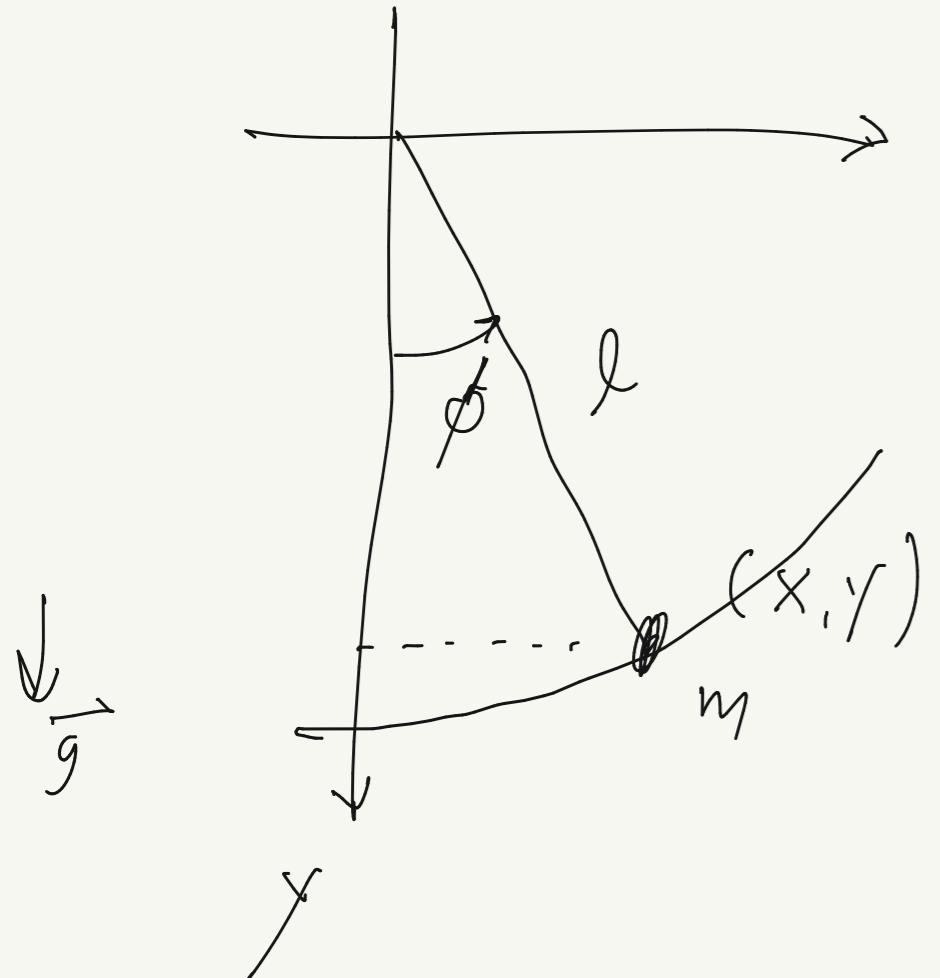
$$\phi(t) = A e^{-i \sqrt{\frac{g}{l}} t}$$

Complex

$$= c_1 \cos(\omega_0 t) + c_2 \sin(\omega_0 t)$$

$$= a \cos(\omega_0 t + \alpha)$$

Lagrangian formulation:



$$L = T - U$$

$$U = -mgx \\ = -mgl \cos\phi$$

$$y = l \cos\phi \\ x = l \sin\phi$$

$$T = \frac{1}{2}m(x^2 + y^2) \\ = \frac{1}{2}m l^2 \dot{\phi}^2$$

$$\dot{x} = l\dot{\phi} \cos\phi \\ \dot{y} = -l\dot{\phi} \sin\phi$$

$$L = \frac{1}{2}m l^2 \dot{\phi}^2 + mgl \cos\phi$$

~~Final~~

$$(x, y) \quad x = r \cos\phi \\ (r, \phi) \quad y = r \sin\phi$$

$$T = \frac{1}{2}m(r^2 + r^2\dot{\phi}^2)$$

Lagrange's equations

$$\frac{d}{dt} \left(\frac{\partial L}{\partial \dot{\phi}} \right) = \frac{\partial L}{\partial \phi}$$

$$\frac{d}{dt}(ml^2\dot{\phi}) = -mgl \sin\phi$$

$$ml^2\ddot{\phi} = -mgl \sin\phi$$

$$\ddot{\phi} = -\frac{g}{l} \sin\phi$$

L does not depend explicitly on time $t \rightarrow E$ is conserved.

$$E = \sum_i \frac{\partial L}{\partial \dot{q}_i} \dot{q}_i - L$$

$$= T + U$$

Example:

$$\boxed{E} = \frac{\partial L}{\partial \dot{\phi}} \phi - L$$

$$= ml^2 \dot{\phi} \ddot{\phi} - \left(\frac{1}{2} ml^2 \dot{\phi}^2 + mgl \cos \phi \right)$$

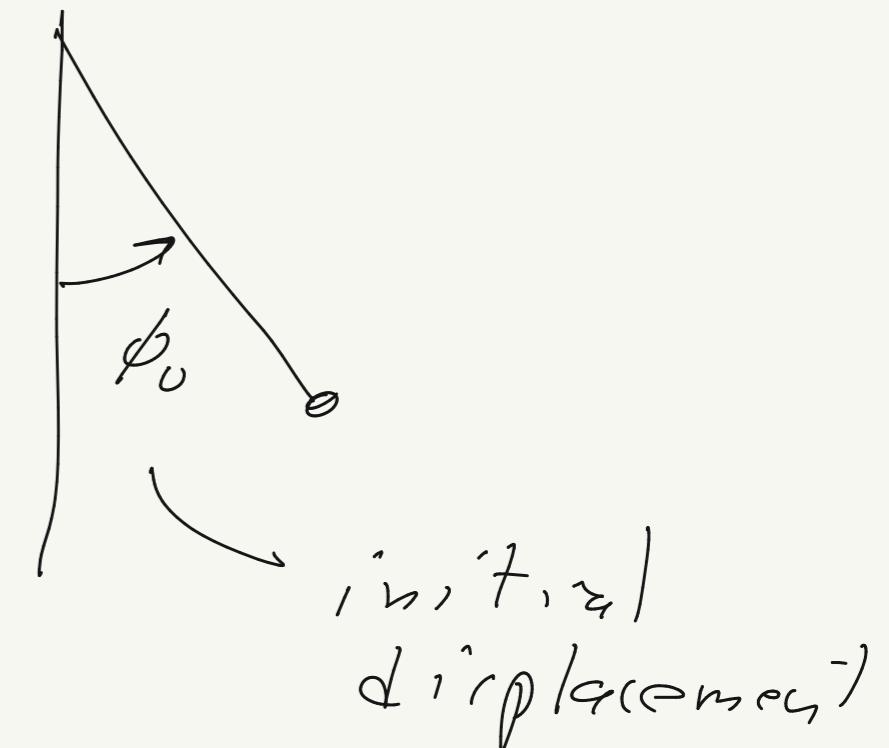
$$= \frac{1}{2} ml^2 \dot{\phi}^2 - mgl \cos \phi$$

$$= T + U$$

$$E = -mgl \cos \phi_0$$

$$-mgl \cos \phi_0 = \frac{1}{2} ml^2 \dot{\phi}^2 - mgl \cos \phi$$

$$\dot{\phi}^2 = \frac{2}{l^2} (gl \cos \phi - gl \cos \phi_0)$$



L & L 11.1

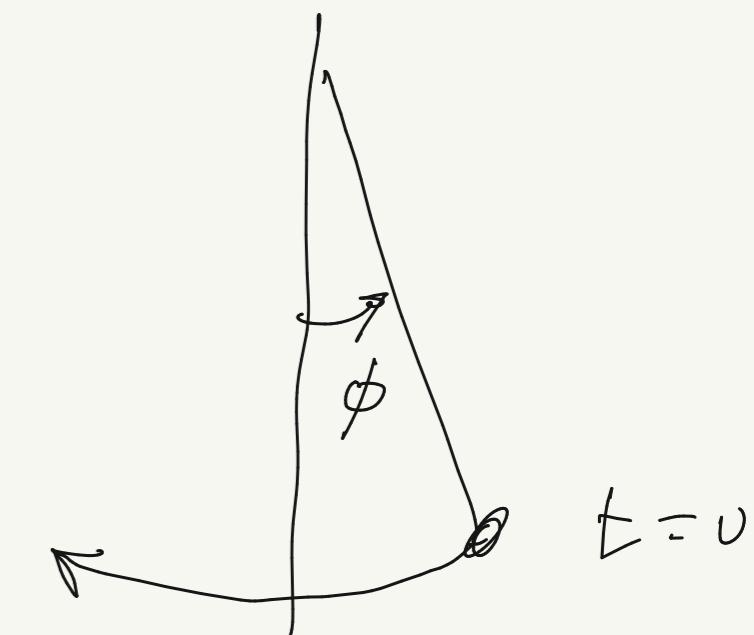
$$\dot{\phi}^2 = 2 \frac{g}{l} (\cos \phi - \cos \phi_0)$$

$$\frac{d\phi}{dt} = \dot{\phi} = \pm \sqrt{2 \frac{g}{l} \sqrt{\cos \phi - \cos \phi_0}}$$

$$\int_{\phi_0}^{\phi} dt = \int_{0}^{t} \frac{-d\phi}{\sqrt{2 \omega_0 \sqrt{\cos \phi - \cos \phi_0}}}$$

$$\omega_0 t + \text{const} = \pm \int \frac{d\phi}{\sqrt{2 \sqrt{\cos \phi - \cos \phi_0}}}$$

$$\int \frac{dx}{\sqrt{ax^2 + bx + c}} =$$



$$\cos \phi = \cos \left(2 \cdot \frac{\phi}{2} \right) = \cos^2 \left(\frac{\phi}{2} \right) - \sin^2 \left(\frac{\phi}{2} \right) = 1 - 2 \sin^2 \left(\frac{\phi}{2} \right)$$

$$\cos \phi_0 = 1 - 2 \sin^2 \left(\frac{\phi_0}{2} \right)$$

$$\Rightarrow \sqrt{\cos \phi - \cos \phi_0} = \sqrt{2} \sqrt{\sin^2 \left(\frac{\phi_0}{2} \right) - \sin^2 \left(\frac{\phi}{2} \right)} = \sqrt{2} \left| \sin \left(\frac{\phi_0}{2} \right) \right| \sqrt{1 - \frac{\sin^2 \left(\frac{\phi_0}{2} \right)}{\sin^2 \left(\frac{\phi}{2} \right)}}$$

$$\int \frac{dt}{\sqrt{1-t^2}} = \sin^{-1} t + \text{const}$$

$$k = \left| \sin\left(\frac{\phi_0}{2}\right) \right| \quad (0 < \tau < 1)$$

$$x = \frac{\sin\left(\frac{\phi}{2}\right)}{\left| \sin\left(\frac{\phi_0}{2}\right) \right|} = \frac{\sin\left(\frac{\phi}{2}\right)}{\tau} \rightarrow dx = \frac{1}{\tau} \frac{1}{2} \cos\left(\frac{\phi}{2}\right) d\phi$$

$\sqrt{2} \sqrt{\cos\phi - \cos\phi_0} = 2\tau \sqrt{1-x^2}$

$$dx = \frac{1}{2\tau} \sqrt{1 - \sin^2\left(\frac{\phi}{2}\right)} d\phi$$

$$d\phi = \frac{2\tau dx}{\sqrt{1 - \tau^2 x^2}}$$

$$w_0 t + \text{const} = \pm \int \frac{2\tau dx}{\sqrt{1 - \tau^2 x^2}} \rightarrow 2\tau \int \frac{dx}{\sqrt{1 - x^2}}$$

$$= \int_0^x \frac{dx}{\sqrt{1-x^2} \sqrt{1-\tau^2 x^2}}$$

$$= \sin^{-1}(x; \tau)$$

$$\left\{ \begin{array}{l} x = \sin\left(\frac{\phi}{2}\right) \\ \tau = \left| \sin\left(\frac{\phi_0}{2}\right) \right| \end{array} \right.$$

$$t = 0 \iff \phi = \phi_0$$

$$\text{const} = \int_0^1 \frac{dx}{\sqrt{1-x^2} \sqrt{1-H^2 x^2}} = K(H)$$

complete elliptic
integral of the
1st kind

$$\omega_0 t + E(K) = \sin^{-1} \left(\frac{\sin(\frac{\phi}{2})}{K} \right); \quad | \quad K \equiv \sin(\frac{\phi_0}{2})$$

$$\sin(\omega_0 t + E(K); K) = \frac{1}{K} \sin\left(\frac{\phi}{2}\right)$$

→ $\phi(t) = 2 \arcsin \left(K \sin(\omega_0 t + E(K); K) \right)$

$$P = \frac{4}{\omega_0} E(K) \quad \rightarrow \quad \frac{\omega_0 P}{4} = E(K)$$

Lec # 4:

2 Sep 2021

$$\omega_0 \int_0^t dt = - \int_{\phi_0}^{\phi} \frac{d\phi}{\sqrt{\theta}}$$

$$\omega_0 t = - \left[\int_{\phi_0}^0 + \int_0^{\phi} \right] \frac{d\phi}{\sqrt{\theta}}$$

$$= + \int_0^{\phi_0} \frac{d\phi}{\sqrt{\theta}} - \int_0^{\phi} \frac{d\phi}{\sqrt{\theta}}$$

$$= \int_0^1 \frac{dx}{\sqrt{1-x^2} \sqrt{1-\frac{\theta}{\theta_0}x^2}} - \int_0^x \frac{dx}{\sqrt{1-x^2} \sqrt{1-\frac{\theta}{\theta_0}x^2}}$$

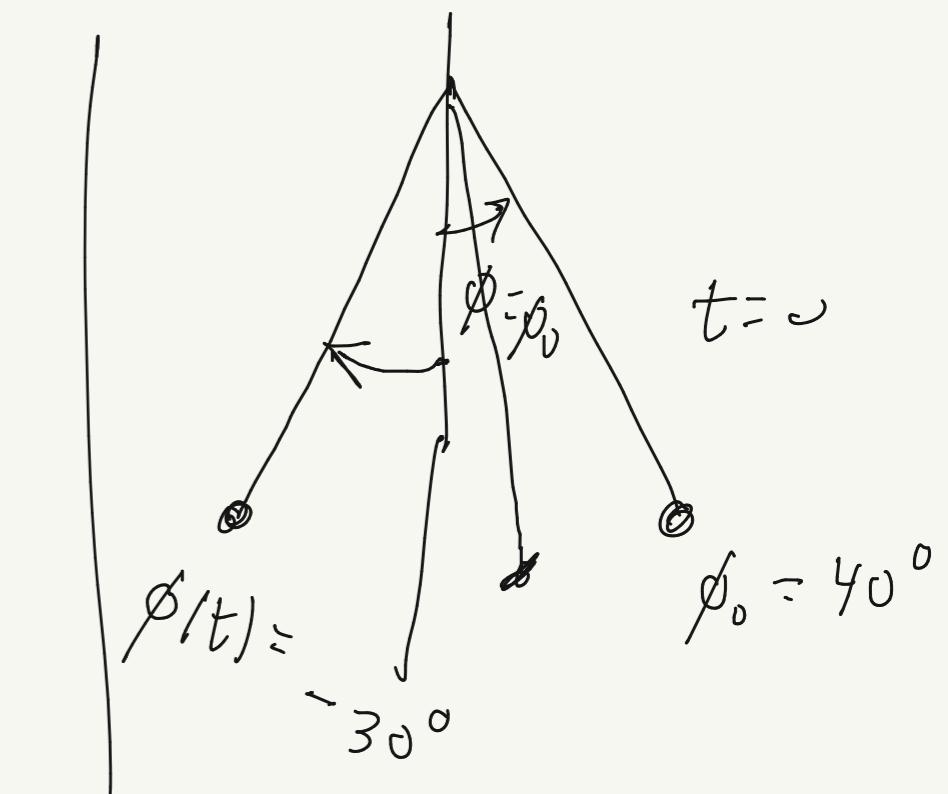
$$= \bar{E}(k) - \operatorname{sn}^{-1}(x; k)$$

$$\operatorname{sn}^{-1}(x; k) = \bar{E}(k) - \omega_0 t$$

$$\frac{\operatorname{sn}(\phi)}{k} = x = \operatorname{sn} \left[\bar{E}/k - \omega_0 t; k \right] = \operatorname{cn}(\omega_0 t; k)$$

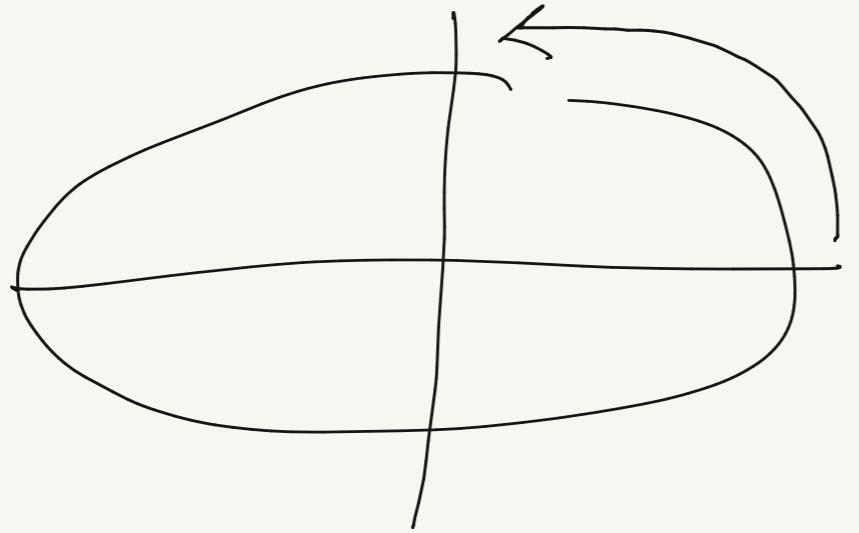
$w_0 = \sqrt{\frac{g}{l}}$

→ $\phi(t) = 2 \arcsin \left(k \operatorname{sn} \left(\bar{E}/k - \omega_0 t; k \right) \right)$



$$x = \frac{\operatorname{sn} \left(\frac{\phi}{k} \right)}{\operatorname{sn} \left(\frac{\phi_0}{k} \right)}$$

$$k = \sqrt{\frac{g}{l \sin \left(\frac{\phi_0}{k} \right)}}$$



$$\frac{1}{\sqrt{1-\pi^2 x^2}} \approx 1 + \frac{1}{2} \pi^2 x^2$$

$$(1+\epsilon)^P \approx 1 + P\epsilon$$

$$\omega_0 \frac{P}{g} = K(\pi)$$

$$\rightarrow \boxed{P = \frac{4}{\omega_0} E(\pi)}$$

$$K(\pi) = \int_0^1 \frac{dx}{\sqrt{1-x^2} \sqrt{1-\pi^2 x^2}}$$

$\pi=0$: $K(0) = \int_0^1 \frac{dx}{\sqrt{1-x^2}} = \sin^{-1} 1 = \frac{\pi}{2}$

$$P = \frac{4}{\omega_0} \frac{\pi}{2} = \frac{2\pi}{\omega_0} = 2\pi \sqrt{\frac{k}{g}}$$

$$0 < \pi < < 1$$

$$K(\pi) = \int_0^1 \frac{dx}{\sqrt{1-x^2}} \left(1 + \frac{1}{2} \pi^2 x^2 \right) = \frac{\pi}{2} + \int_0^1 \frac{dx}{\sqrt{1-x^2}} \frac{1}{2} \pi^2 x^2$$

$$\sin\left(\frac{\pi}{2} - \theta\right) = \cos \theta$$

Pf: $\sin\left(\frac{\pi}{2} - \theta\right) = \underbrace{\sin\left(\frac{\pi}{2}\right)}_{=1} \cos \theta - \cancel{\cos\left(\frac{\pi}{2}\right)} \sin \theta$

$$= \cos \theta$$

$$\sin(-\theta) = -\sin \theta, \quad \cos(-\theta) = \cos \theta$$

$$\sin(\pi - x; \pi) = \sin(x)$$

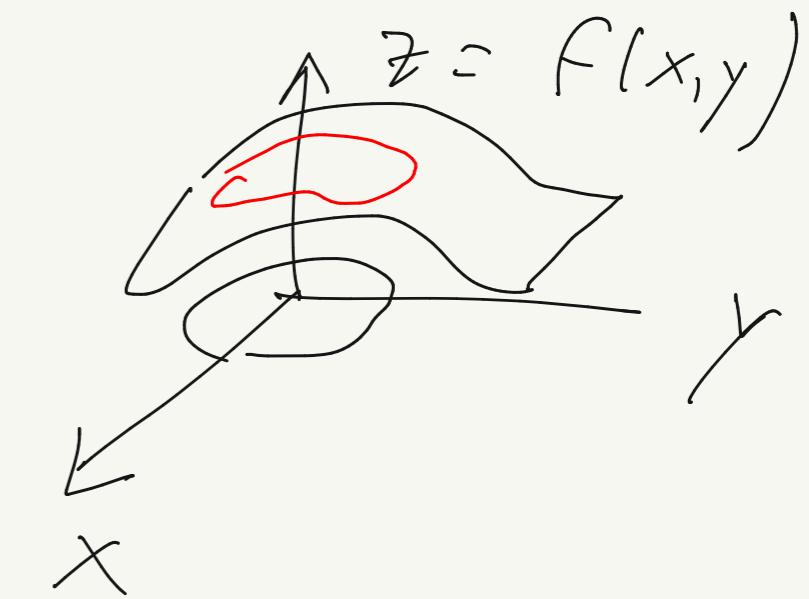
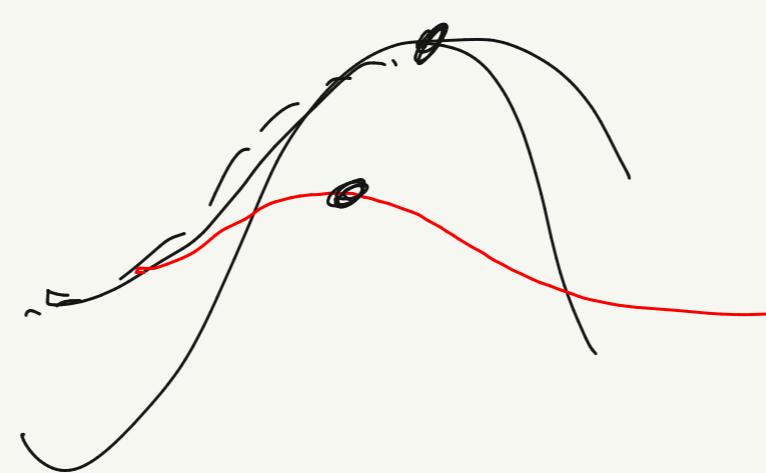
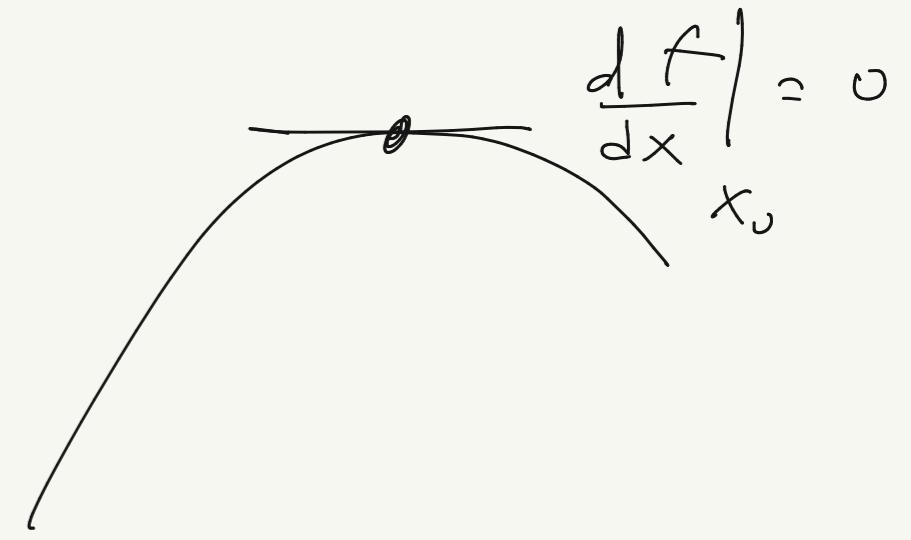
Lagrange multipliers

$f(x) : \max \text{ or } \min ?$

$f(x, y) :$ If

$$\frac{df}{dx} = 0$$

$$\frac{\partial f}{\partial x} = 0, \quad \frac{\partial f}{\partial y} = 0$$



$f(x, y) : \text{Find extreme value subject to constraint } g(x, y) = 0 ?$

1) "reduced square method":

solve constraint $g(x, y) = 0 \rightarrow y = g(x)$

$$F(x) = f(x, y)$$

e.g., $x^2 + y^2 = 1$

$$2x dx + 2y dy = 0$$

2) "method of Lagrange multipliers"

$$F(x, y, \lambda) = f(x, y) + \lambda g(x, y)$$

$$\begin{cases} \frac{\partial F}{\partial x} = 0 \\ \frac{\partial F}{\partial y} = 0, \quad \frac{\partial F}{\partial \lambda} = 0 \end{cases}$$

$$dx = -\frac{y}{x} dy$$

$$\frac{\partial F}{\partial x} = \frac{\partial f}{\partial x} + \lambda \frac{\partial \varphi}{\partial x} = 0$$

$$F(x, y, \lambda) = f(x, y) + \lambda \varphi(x, y)$$

$$\frac{\partial F}{\partial y} = \frac{\partial f}{\partial y} + \lambda \frac{\partial \varphi}{\partial y} = 0$$

$$\frac{\partial F}{\partial \lambda} = \varphi(x, y) = 0$$

$$\varphi(r, \phi) = 0 = r - l$$

$$L(f(r, \phi, \dot{r}, \dot{\phi}, t)) + \lambda(r - l) = L'$$

$\varphi(r, \phi)$

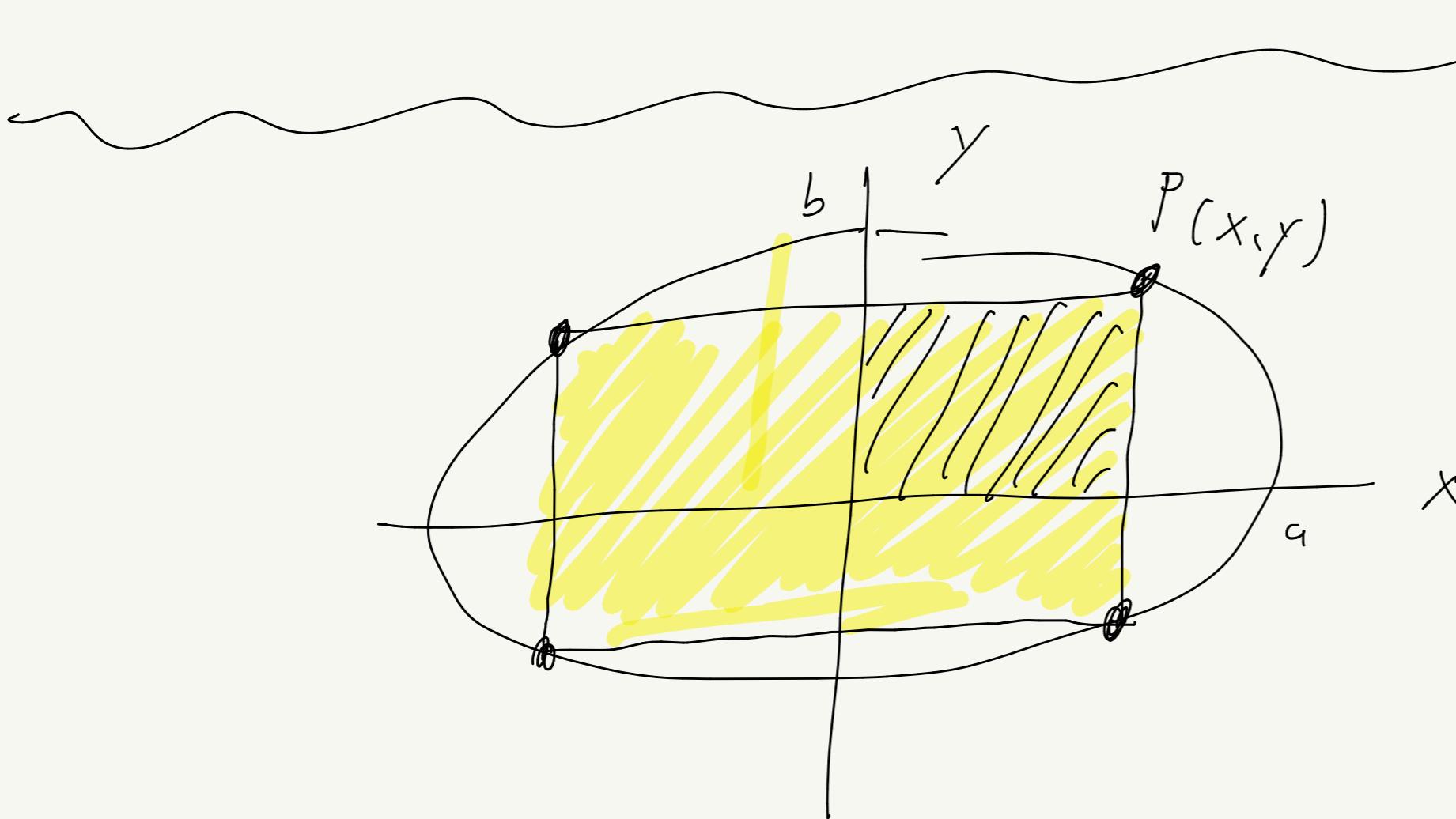
$$\frac{d}{dt} \left(\frac{\partial L'}{\partial \dot{q}} \right) = \frac{\partial L'}{\partial q}$$

$$\frac{d}{dt} \left(\frac{\partial L}{\partial \dot{q}} \right) = \frac{\partial L}{\partial q} + \lambda \frac{\partial \varphi}{\partial q}$$

$$\frac{dP}{dt} = - \frac{\partial U}{\partial q} + \lambda \frac{\partial \varphi}{\partial q} = F_{pp} + F_{constraint}$$

1) Lagrange multipliers

2) Example: 2-d oscillating orbit



Maximize the area of a rectangle whose corners lie on the ellipse

$$\rightarrow \left(\frac{x}{a}\right)^2 + \left(\frac{y}{b}\right)^2 = 1$$

$$A(x, y) = 4xy$$

$$\varphi(x, y) = 1 - \left(\frac{x}{a}\right)^2 - \left(\frac{y}{b}\right)^2 = 0$$

$$F(x, y, \lambda) = 4xy + \lambda \varphi(x, y)$$

$\frac{\partial F}{\partial x} = 4y + \lambda \left(-\frac{2x}{a^2}\right) = 0$
$\frac{\partial F}{\partial y} = 4x + \lambda \left(-\frac{2y}{b^2}\right) = 0$
$\frac{\partial F}{\partial \lambda} = 1 - \left(\frac{x}{a}\right)^2 - \left(\frac{y}{b}\right)^2 = 0$

$$\frac{\partial F}{\partial x} = 4x + \lambda \left(-\frac{2x}{a^2} \right) = 0$$

$$4y^2a^2 - 2\lambda xy = 0$$

~~cancel~~

$$\frac{\partial F}{\partial y} = 4x + \lambda \left(-\frac{2y}{b^2} \right) = 0$$

$$4x^2b^2 - 2\lambda yx = 0$$

~~cancel~~

$$\frac{\partial F}{\partial \lambda} = 1 - \left(\frac{x}{a}\right)^2 - \left(\frac{y}{b}\right)^2 = 0 \quad \leftarrow$$

subtract

$$4y^2a^2 - 4x^2b^2 = 0$$

$$x^2a^2 = x^2b^2$$

$$\frac{x}{a} = \pm \frac{x}{b}$$

~~cancel~~

$$0 = 1 - \left(\frac{x}{a}\right)^2 - \left(\frac{y}{b}\right)^2$$

$$= 1 - 2\left(\frac{x}{a}\right)^2$$

$$\frac{x}{a} = \pm \frac{1}{\sqrt{2}}$$

$$x = \frac{a}{\sqrt{2}}$$

$$y = \frac{b}{\sqrt{2}}$$

$$A_{max} = 4xy \\ = 4 \frac{a}{\sqrt{2}} \frac{b}{\sqrt{2}}$$

$$= 2ab$$

Reduced Space method

$$F(x) = 4 \cancel{xy} \quad | \\ y = b \sqrt{1 - \left(\frac{x}{a}\right)^2}$$

$$\left(\frac{x}{a}\right)^2 + \left(\frac{y}{b}\right)^2 = 1 \\ y = b \sqrt{1 - \left(\frac{x}{a}\right)^2}$$

$$= 4b \times \sqrt{1 - \left(\frac{x}{a}\right)^2}$$

maximize:

$$0 = F'(x) = 4b \sqrt{\quad} + 4b \times \left(\frac{1}{\cancel{b}}\right) \frac{1}{\sqrt{\quad}} \left(-\frac{\cancel{2x}}{a^2} \right)$$

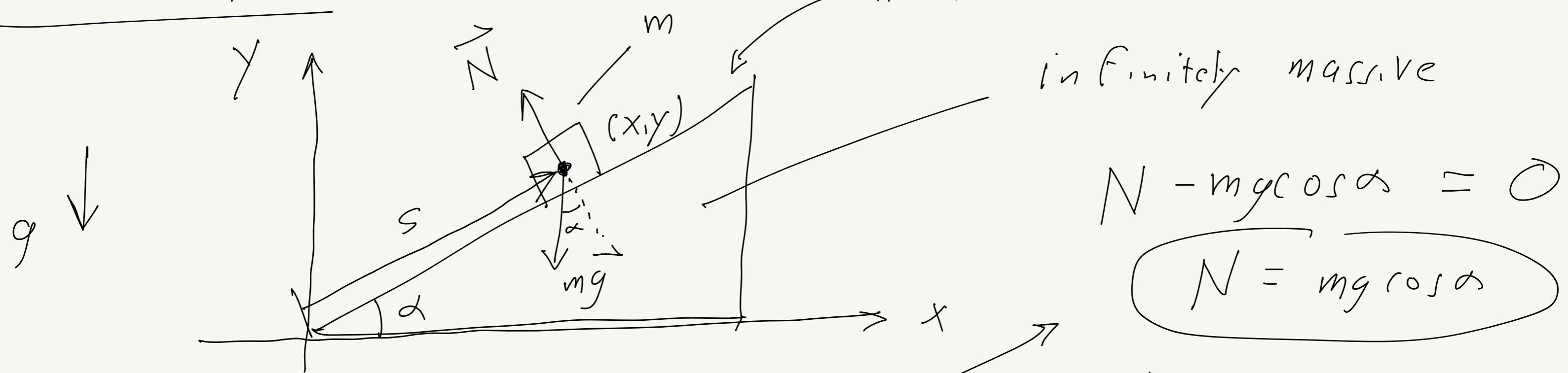
$$= 4b \left(\sqrt{\quad} = \left(\frac{x}{a}\right)^2 \frac{1}{\sqrt{\quad}} \right)$$

$$= \frac{4b}{\sqrt{\quad}} \left(1 - \left(\frac{x}{a}\right)^2 - \left(\frac{x}{a}\right)^2 \right)$$

$$= \frac{4b}{\sqrt{\quad}} \left(1 - 2 \left(\frac{x}{a}\right)^2 \right) \rightarrow \left(\frac{x}{a}\right)^2 = \frac{1}{2}$$

$$x = \pm \frac{a}{\sqrt{2}}$$

Mechanics problem:



Freshman physics analysis:

$$m s' = -mg \sin \alpha$$

$$s' = -g \sin \alpha$$

Lagrangian analysis:

$$x = s \cos \alpha, y = s \sin \alpha$$

$$\frac{y}{x} = \tan \alpha$$

$$T = \frac{1}{2} m (\dot{x}^2 + \dot{y}^2)$$

$$y = x \tan \alpha$$

$$U = mg y$$

$$\varphi(x, y) = y - x \tan \alpha = 0$$

$$L = \frac{1}{2} m (\dot{x}^2 + \dot{y}^2) - mg y$$

$$L' = L + \lambda \varphi$$

$$F = A + \lambda \varphi$$

$$= \frac{1}{2} m(\dot{x}^2 + \dot{y}^2) - mgx + \lambda(y - x \tan \alpha)$$

$$\frac{d}{dt} \left(\frac{\partial L'}{\partial \dot{x}} \right) = \frac{\partial L'}{\partial x}$$

$$\rightarrow \frac{d}{dt} \left(\frac{\partial L}{\partial \dot{x}} \right) = \frac{\partial L}{\partial x} + \lambda \frac{\partial \varphi}{\partial x}$$

$$\frac{d p_x}{dt} = F_x + \lambda \frac{\partial \varphi}{\partial x}$$

$$\frac{d p_y}{dt} = F_y + \lambda \frac{\partial \varphi}{\partial y}$$

$$\frac{d \vec{p}}{dt} = \vec{F} + \lambda \vec{\nabla} \varphi$$

$$\frac{d}{dt} \left(\frac{\partial L}{\partial \dot{y}} \right) = \frac{\partial L}{\partial y} + \lambda \frac{\partial \varphi}{\partial y}$$

$$\varphi(x, y) = y - x \tan \alpha = 0$$

$$\frac{d}{dt}(m \dot{x}) = 0 + \lambda(-\tan \alpha)$$

$$\rightarrow m \ddot{x} = -\lambda \tan \alpha$$

$$\frac{d}{dt}(m \dot{y}) = -mg + \lambda$$

$$\ddot{x} = -\frac{1}{m} \tan \alpha$$

$$\ddot{y} = -g + \frac{\lambda}{m}$$

$$y - x \tan \alpha = 0$$

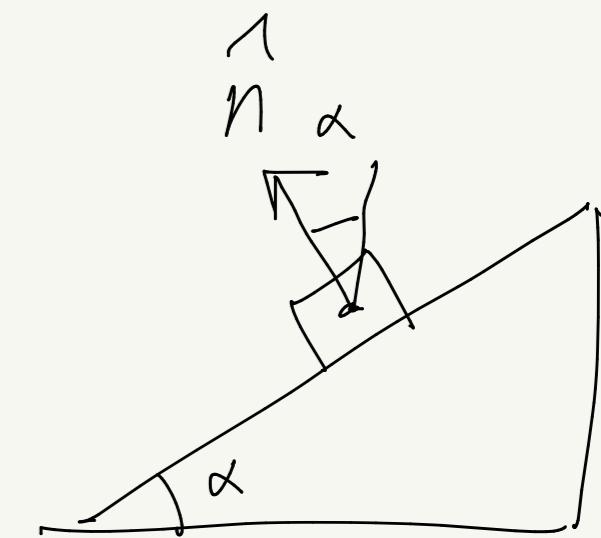
$$y - \dot{x} \tan \alpha = 0 \rightarrow \dot{y} = \dot{x} \tan \alpha$$

$$\left(-g + \frac{\lambda}{m} \right) = -\frac{\lambda}{m} \tan \alpha \cdot \tan \alpha$$

$$\phi = y - x \tan \alpha$$

$$\frac{\lambda}{m} (1 + \tan^2 \alpha) = g$$

$$\sec^2 \alpha = \frac{1}{\cos^2 \alpha}$$



$$\frac{\lambda}{m} = g \cos^2 \alpha$$

$$\lambda = mg \cos^2 \alpha$$

$$\vec{F}_c = \lambda \vec{\nabla} \phi$$

$$= \lambda (\vec{y} - \vec{x} \tan \alpha)$$

unit

$$\vec{F}_c = \lambda \left(\vec{y} - \vec{x} \frac{\sin \alpha}{\cos \alpha} \right)$$

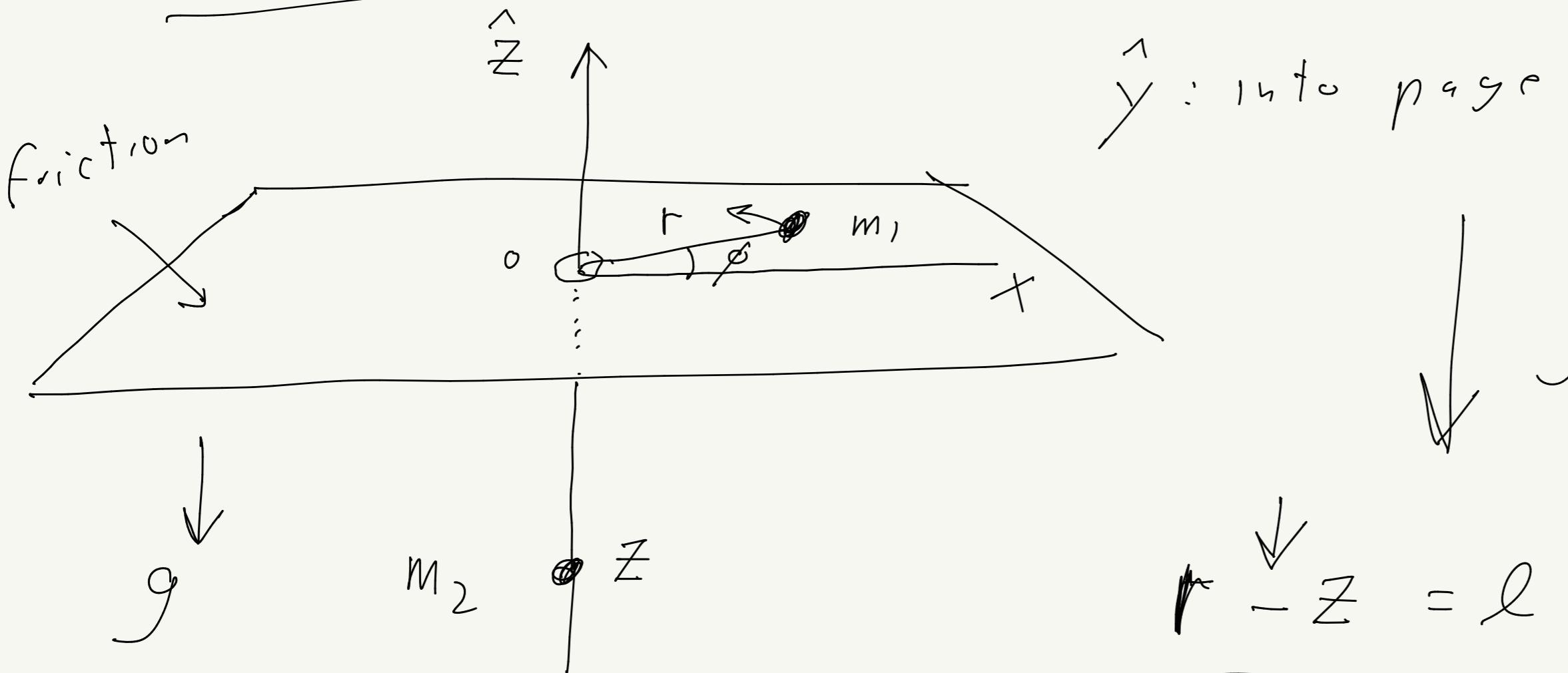
$$= \frac{\lambda}{\cos \alpha} \left(\cos \alpha \vec{y} - \vec{x} \sin \alpha \right)$$

$$= \frac{\lambda}{\cos \alpha} \vec{n} = \boxed{mg \cos \alpha \vec{n}}$$

Q.

2-d Example:

string length = ℓ



$$x = r \cos \phi$$

$$y = r \sin \phi$$

$$r - z = \ell$$

$$z = r - \ell$$

$$\begin{aligned} T &= \frac{1}{2} m_1 (\dot{x}^2 + \dot{y}^2) + \frac{1}{2} m_2 \dot{z}^2 \\ &= \frac{1}{2} m_1 (\dot{r}^2 + r^2 \dot{\phi}^2) + \frac{1}{2} m_2 \dot{r}^2 \\ &= \frac{1}{2} (m_1 + m_2) \dot{r}^2 + \frac{1}{2} m_1 r^2 \dot{\phi}^2 \end{aligned}$$

igno-
1 (con, +)

$$U = m_2 g z = m_2 g (r - \ell) = m_2 gr$$

~~$m_2 g l$~~

$$L = T - U$$

$$= \frac{1}{2} (m_1 + m_2) \dot{r}^2 + \frac{1}{2} m_1 r^2 \dot{\phi}^2 - m_2 g r$$

$$(r, \phi) \quad \frac{d}{dt} \left(\frac{\partial L}{\partial \dot{r}} \right) = \frac{\partial L}{\partial r}$$

$$\frac{d}{dt} \left(\frac{\partial L}{\partial \dot{\phi}} \right) = \cancel{\frac{\partial L}{\partial \phi}} = 0$$

$$\frac{\partial L}{\partial \dot{\phi}} = \text{const} = \boxed{m_1 r^2 \dot{\phi} = M_2}$$

No explicit time-dependence:

$$E = \text{const} = \underbrace{\sum_i \frac{\partial L}{\partial \dot{q}_i} \dot{q}_i}_{\sim} - L = \overbrace{T + U}$$

~~scribble~~

$$E = \frac{1}{2}(m_1 + m_2) \dot{r}^2 + \frac{1}{2} m_1 r^2 \dot{\phi}^2 + m_2 g r$$

const.

$M_z = m_1 r^2 \dot{\phi}$ \rightarrow $\dot{\phi} = \frac{M_z}{m_1 r^2}$

$$\rightarrow E = \frac{1}{2}(m_1 + m_2) \dot{r}^2 + \frac{1}{2} m_1 r^2 \left(\frac{M_z}{m_1 r^2} \right)^2 + m_2 g r$$

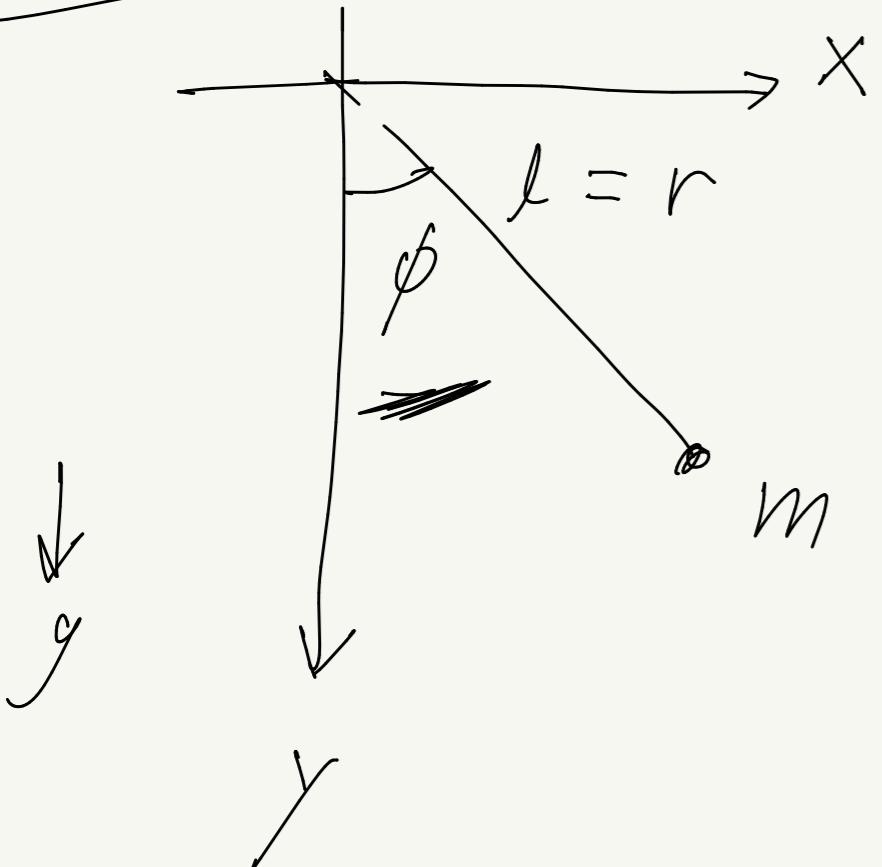
$$= \frac{1}{2}(m_1 + m_2) \dot{r}^2 + \frac{M_z^2}{2 m_1 r^2} + m_2 g r$$

$\underbrace{\qquad\qquad\qquad}_{U_{eff}(r)}$

Lec #6:

Sept. 9th

Quiz #1



Calculate tension in the string
using the method of
Lagrange multipliers.

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constraint:

$$\underline{\phi} = \ell - r = 0$$

$$U = -mg y$$

$$= -mg r \cos \phi$$

$$\vec{F}_c = \lambda \vec{\nabla} \phi$$

$$L = T - U$$

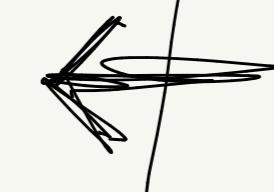
$$= \frac{1}{2} m (\dot{r}^2 + r^2 \dot{\phi}^2) + m g r \cos \phi$$

Eric
Niramay
Muhammad

$$(1) \frac{d}{dt} \left(\frac{\partial L}{\partial \dot{r}} \right) = \frac{\partial L}{\partial r} + \lambda \frac{\partial \phi}{\partial r}$$

$$(2) \frac{d}{dt} \left(\frac{\partial L}{\partial \dot{\phi}} \right) = \frac{\partial L}{\partial \phi} + \lambda \frac{\partial \phi}{\partial \phi}$$

$$\begin{cases} \phi = 0 \\ \rightarrow r = \ell \end{cases} \quad (3)$$



$$\frac{d}{dt}(mr) = mr\dot{\phi}^2 + mg \cos\phi - \lambda$$

$$mr'' = mr\dot{\phi}^2 + mg \cos\phi - \lambda$$

$$(1) ml^2\ddot{\phi} = -mgls\sin\phi$$

$$\frac{d}{dt}(mr^2\dot{\phi}) = -mg r s\sin\phi$$

$$2mr\dot{r}\dot{\phi} + mr^2\ddot{\phi} = -mg r s\sin\phi$$

$$(2) \ddot{\phi} = \frac{-g s\sin\phi}{l}$$

$$\boxed{r=l} \rightarrow \boxed{\dot{r}=0}, \boxed{\ddot{r}=0}$$

(3)

$$\varphi = l - r$$

$$0 = ml\dot{\phi}^2 + mg \cos\phi - \lambda$$

$$\cancel{\lambda} = ml\dot{\phi}^2 + mg \cos\phi$$

$$\nabla\varphi = -\vec{r}$$

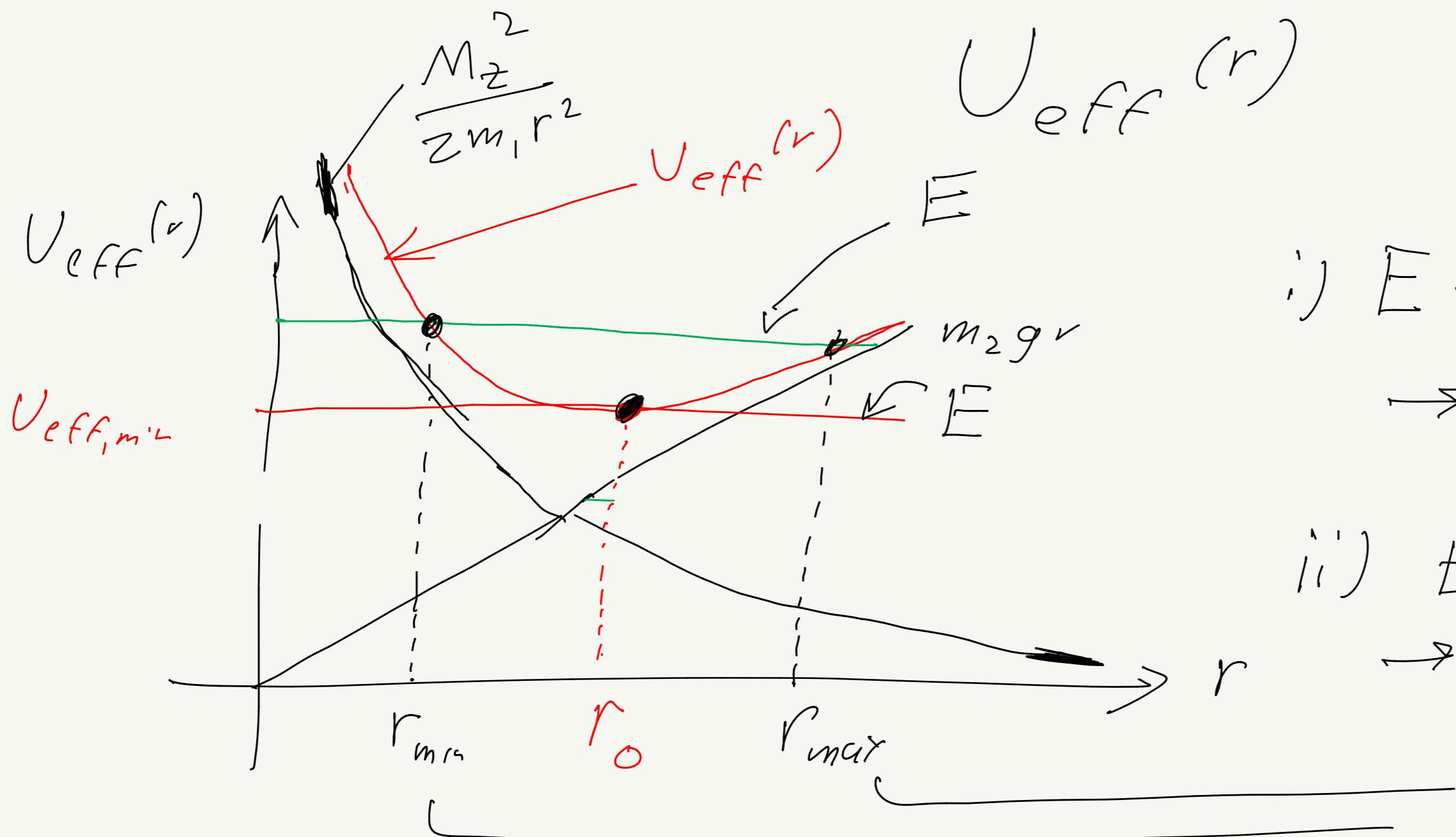
$$\begin{aligned} \cancel{\lambda - mg \cos\phi} \\ = ml\dot{\phi}^2 \end{aligned}$$

$$\vec{F}_c = -(ml\dot{\phi}^2 + mg \cos\phi)\vec{r}$$

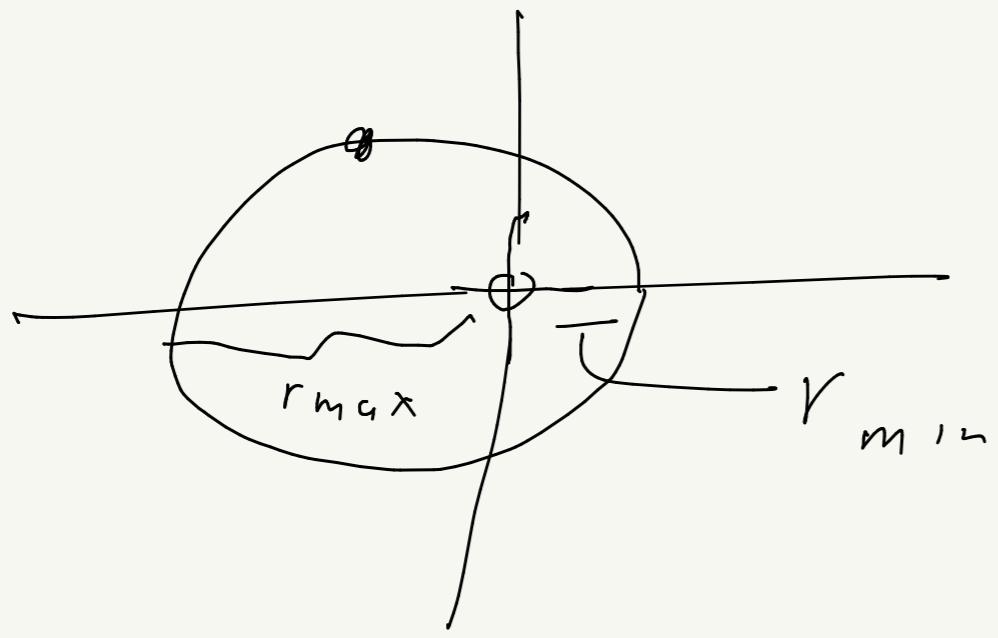
Revisit: oscillating orb. t example

$$E = \frac{1}{2} (m_1 + m_2) \dot{r}^2 + \frac{1}{2} m_1 r^2 \left(\frac{M_2}{m_1 r^2} \right)^2 + m_2 g r$$

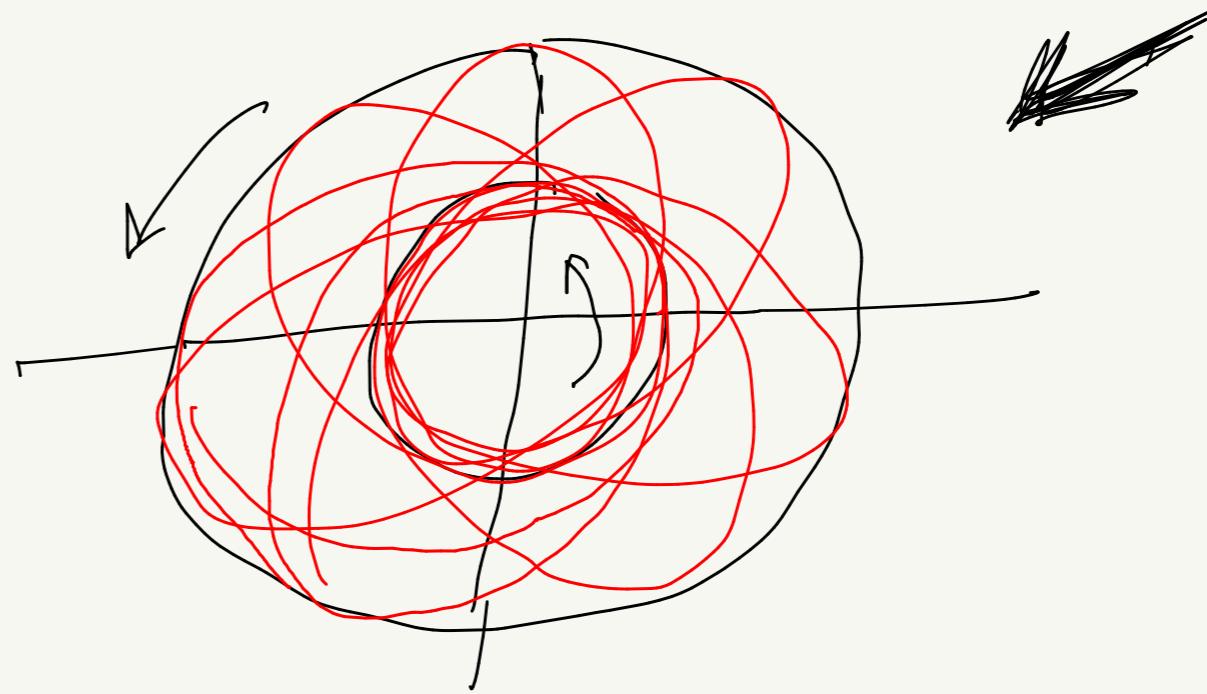
$$= \frac{1}{2} (m_1 + m_2) \dot{r}^2 + \frac{\frac{M_2^2}{2 m_1 r^2}}{+ m_2 g r}$$



- $E \geq U_{\text{eff}, \text{min}}$
- i) $E = U_{\text{eff}, \text{min}}$
→ stable circul-
orb.t $r = r_0$
 - ii) $E > U_{\text{eff}, \text{min}}$
→ bounded motios
between r_{min} and r_{max}
turning points



closed bound orbit



bound orbit
that's not closed

r_0 : minimum of the effective potential

$$\Omega = \left. \frac{dU_{\text{eff}}}{dr} \right|_{r=r_0} = \left. \left(m_2 g - \frac{M_2^2}{m_1 r^3} \right) \right|_{r=r_0}$$

$$\Omega = m_2 g - \frac{M_2^2}{m_1 r_0^3}$$

$$M_2^2 = m_1 m_2 g r_0^3$$

$$E = \frac{1}{2} (m_1 + m_2) \dot{r}^2 + V_{\text{eff}}(r),$$

$$E - V_{\text{eff}}(r) = \frac{1}{2} (m_1 + m_2) \dot{r}^2$$

$$V_{\text{eff}}(r) = m_2 gr + \frac{M_2^2}{2m_1 r^2}$$

$$\frac{dr}{dt} = \dot{r} = \pm \sqrt{\left(\frac{2}{m_1 + m_2}\right) (E - V_{\text{eff}}(r))}$$

$$\int dt = \pm \int \frac{dr}{\sqrt{\left(\frac{2}{m_1 + m_2}\right)(E - V_{\text{eff}}(r))}} \rightarrow t = t(r)$$

$$M_2 = m_1 r^2 \dot{\phi}$$

$$\dot{\phi} = \frac{M_2}{m_1 r^2}$$

$$\frac{dr}{dt} = \pm \sqrt{\textcircled{1}}$$

$$\frac{dr}{dt} = \frac{dr}{d\phi} \frac{d\phi}{dt} =$$

$$\frac{M_2}{m_1 r^2} \frac{dr}{d\phi}$$

$$\frac{M_2}{m_1 r^2} \frac{dr}{d\phi} = \pm \sqrt{\ell}$$

orb. t eqn_o

$$\int \frac{M_2 dr}{m_1 r^2 \sqrt{\ell}} = \int \pm d\phi$$

$$\rightarrow \phi = \phi(r)$$

$$r = r(\phi)$$

$$\frac{dr}{dt} = \pm \sqrt{\ell}$$

$$\frac{d\phi}{dt} = \frac{M_2}{m_1 r^2}$$

$$\ell = \frac{2}{m_1 + m_2} (E - U_{eff}(r))$$

~~start~~ choose E, M_2, m_1, m_2 , etc.

start system off at some values of r and ϕ at $t=0$

step 1: ~~r_1, ϕ_1~~
step 2: $r_2 = r_1 + \Delta r, \phi_2 = \phi_1 + \Delta \phi$
 (repeat)

Lec #7:

Sep 14th

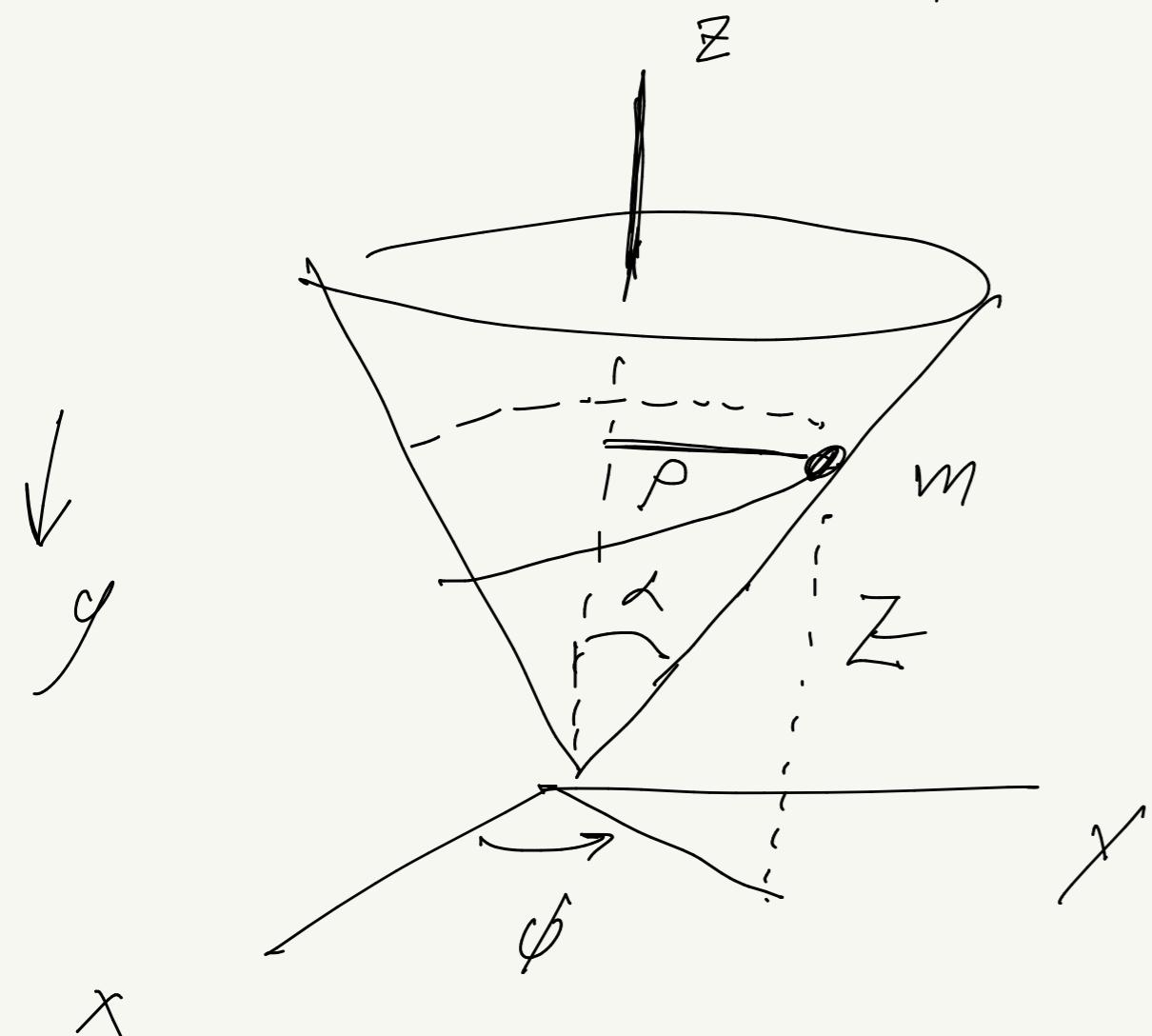
$$\phi(\rho, \phi, z) = \rho - z \tan \alpha = 0$$

Lec #8:

Sep 16th

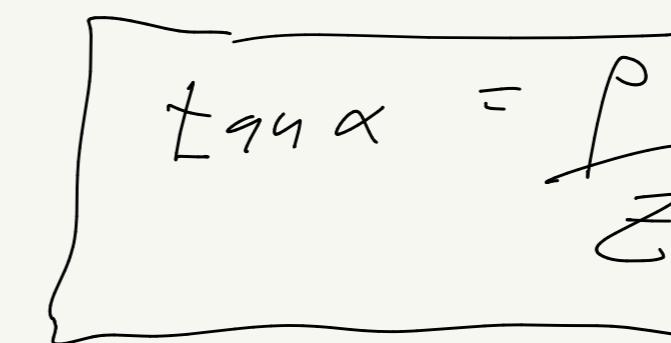
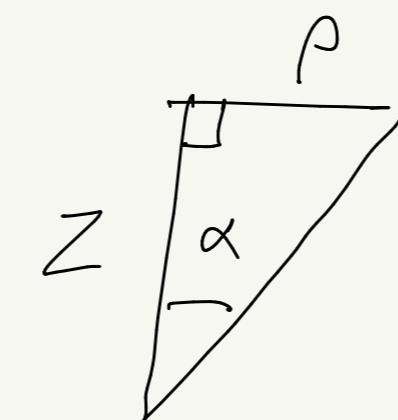
(Q) & A:

Determine constraint force vary
method of Lagrange multiplier



$$U = mgz$$

cylindrical coord (ρ, ϕ, z)

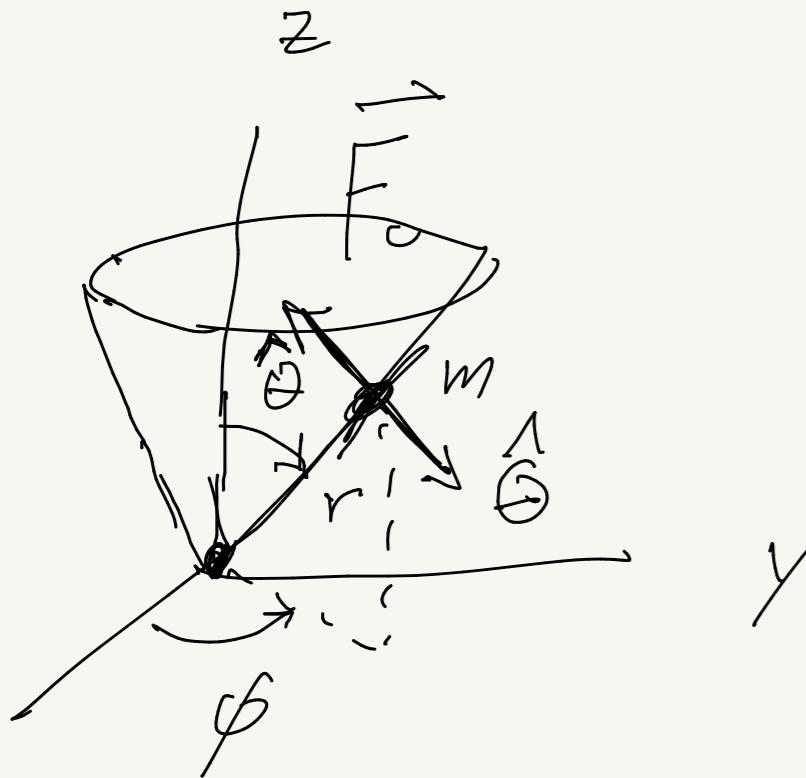


$$\tan \alpha = \frac{z}{\rho} \rightarrow \rho = z \tan \alpha$$

$$T = \frac{1}{2} m (\dot{\rho}^2 + \rho^2 \dot{\phi}^2 + \dot{z}^2) \leftarrow$$

$$= \frac{1}{2} m (z^2 \tan^2 \alpha + z^2 \tan^2 \alpha \dot{\phi}^2 + \dot{z}^2)$$

$$= \frac{1}{2} m (z^2 (1 + \tan^2 \alpha) + z^2 \tan^2 \alpha \dot{\phi}^2)$$



$$T = \frac{1}{2}m(r^2 + r^2\dot{\phi}^2 + r^2 \sin^2\theta \dot{\phi}^2)$$

$$\boxed{\theta = \alpha} = \text{const}$$

$$T = \frac{1}{2}m(r^2 + r^2 \sin^2\alpha \dot{\phi}^2)$$

$$U = mgZ = mgr \cos\alpha$$

x

$$x = r \sin\theta \cos\phi$$

$$y = r \sin\theta \sin\phi$$

$$z = r \cos\theta$$

$$\phi(r, \theta, \phi) = \alpha - \theta = \text{const}$$

constraint

$$L' = \left(\frac{1}{2}m(r^2 + r^2\dot{\phi}^2 + r^2 \sin^2\theta \dot{\phi}^2) - mgr \cos\theta \right) + \lambda(\alpha - \theta)$$

(r, phi), phi, r = l

$$\frac{d}{dt} \left(\frac{\partial L'}{\partial \dot{r}} \right) = \frac{\partial L'}{\partial r}$$

$$\frac{d}{dt} \left(\frac{\partial L'}{\partial \dot{\theta}} \right) = \frac{\partial L'}{\partial \theta}$$

$$\frac{d}{dt} \left(\frac{\partial L'}{\partial \dot{\phi}} \right) = \frac{\partial L'}{\partial \phi}$$

$$\varphi = (\alpha - \theta) = \phi \rightarrow \theta = \alpha$$

Differentiate constraint w/r/t time

$$\dot{\varphi} = 0, \quad \ddot{\varphi} = 0$$

$$\dot{\theta} = \omega$$

$$F_C^L = \lambda \vec{\nabla} \varphi = -\lambda \vec{\omega}$$

$$L' = L + \lambda \varphi$$

T-U

$$\frac{d}{dt} \left(\frac{\partial L}{\partial \dot{r}} \right) = \frac{\partial L}{\partial r} + \lambda \frac{\partial \varphi}{\partial r}$$

etc.

w/r/t time

solve for λ
(algebraic)

Hamiltonian:

$$L = T - U$$

$$H = \left(\sum_i p_i \dot{q}_i - L \right) \quad \left(\frac{dE}{dt} = 0 \text{ if } \frac{\partial L}{\partial t} = 0 \right)$$

$$H(q, p, t)$$

DOF

$q \equiv q_i$ generalized coord,

$$i = 1, \dots, s$$

$p \equiv p_i$ generalized momenta

$$i = 1, \dots, s$$

$$p_i \equiv \frac{\partial L}{\partial \dot{q}_i} \quad (\text{def'n}) = f(q, \dot{q})$$

$$L = \frac{1}{2} m \dot{x}^2 - U(x)$$

Energy conserved?

$$E = \frac{1}{2} m \dot{x}^2 + U(x)$$

Yes because $\frac{\partial L}{\partial t} = 0$

Momentum conjugate to x ?

$$p = \frac{\partial L}{\partial \dot{x}} = m \dot{x} \rightarrow$$

$$\dot{x} = \frac{p}{m}$$

$$\begin{aligned} F &= (p \dot{x} - L)_{\dot{x}} = p/m \\ &= (p \dot{x} - (\frac{1}{2} m \dot{x}^2 - U(x))) \\ &= p \cdot \frac{p}{m} - \frac{1}{2} m \left(\frac{p}{m} \right)^2 + U(x) \\ &= \frac{p^2}{2m} + U(x) \end{aligned}$$

Hamilton's equations:

$$\left\{ \begin{array}{l} \dot{p}_i = -\frac{\partial H}{\partial q_i} \quad i=1, \dots, s \\ \dot{q}_i = \frac{\partial H}{\partial p_i} \end{array} \right. \quad i=1, \dots, s$$

(2s) 1st-order ordinary
differential equations,
(coupled)

Euler-Lagrange
equations:

$$\frac{d}{dt} \left(\frac{\partial L}{\partial \dot{q}_i} \right) = \frac{\partial L}{\partial q_i}$$

$$(i=1, 2, \dots, s)$$

$$L = L(\dot{q}, q)$$

s 2nd order ordinary
diff equations,
(coupled)

$$L = \frac{1}{2} m \dot{x}^2 - U(x)$$

$$H = \frac{p^2}{2m} + U(x)$$

EL equations:

$$\frac{d}{dt} \left(\frac{\partial L}{\partial \dot{x}} \right) = \frac{\partial L}{\partial x}$$

$$m \ddot{x} = - \frac{\partial U}{\partial x}$$

$$(m\ddot{x} = F)$$

-Hamilton's equations:

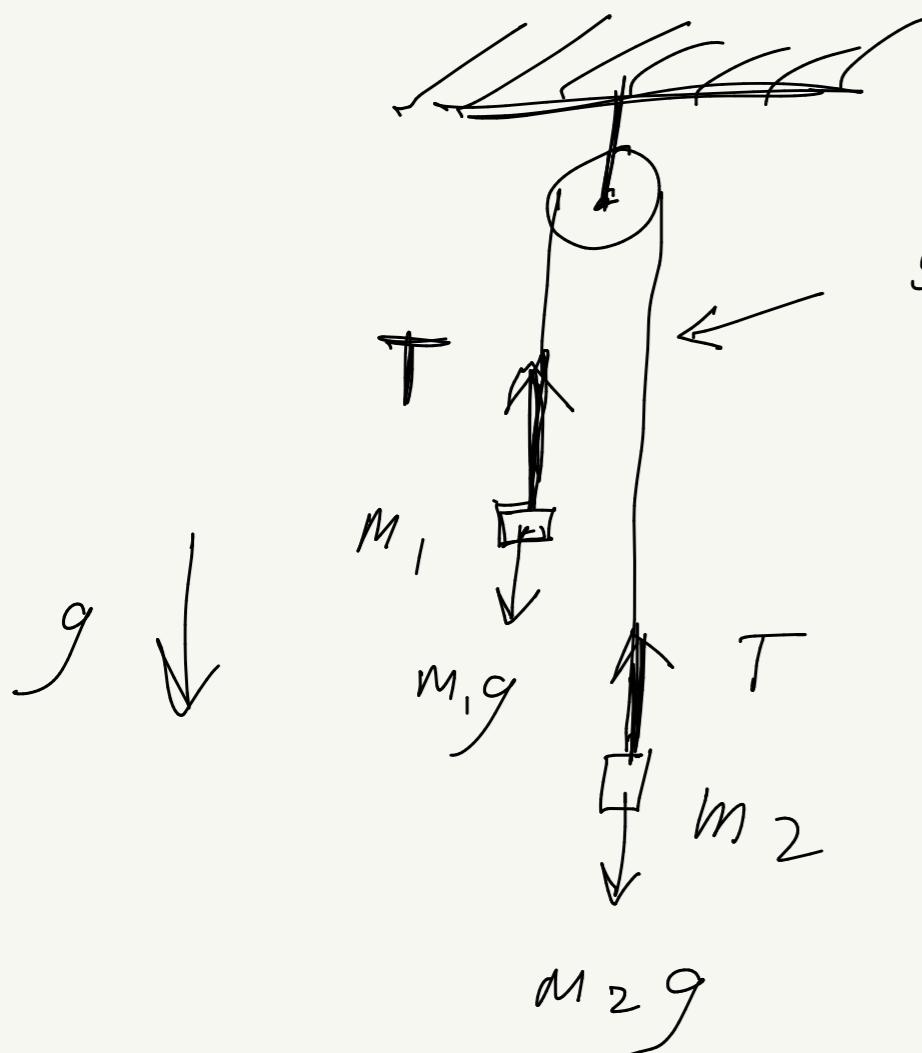
$$\dot{x} = \frac{\partial H}{\partial p} = \frac{p}{m}$$

$$\dot{p} = - \frac{\partial H}{\partial x} = - \frac{\partial U}{\partial x}$$

$$(p = m\dot{x})$$

$$m \ddot{x} = - \frac{\partial U}{\partial x}$$

A 'twood' machine:



$$a = \frac{g(m_1 - m_2)}{m_1 + m_2}$$

(down) ~~up~~

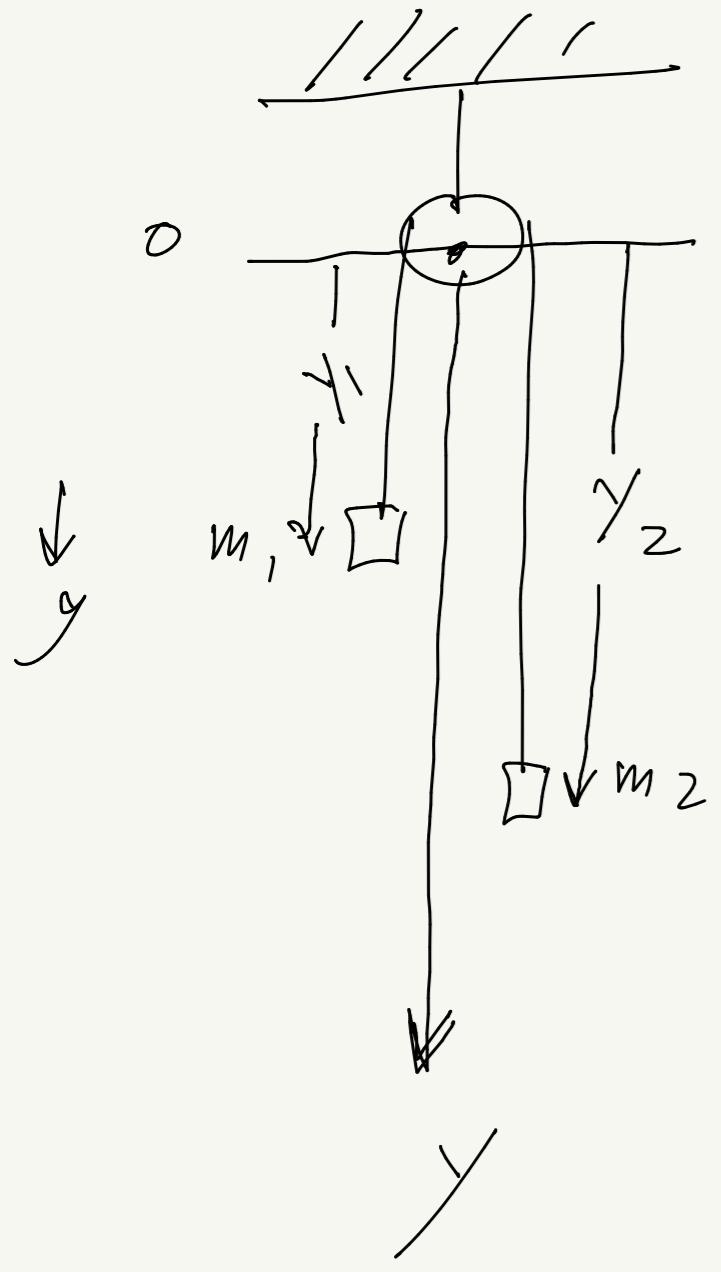
Net force down:

$$m_1 g - T = m_1 a$$

$$m_2 g - T = -m_2 a$$

subtract $(m_1 - m_2)g = (m_1 + m_2)a$

$$a = \frac{(m_1 - m_2)g}{m_1 + m_2}$$



$$L = T - U$$

$$T = \frac{1}{2} m_1 \dot{y}_1^2 + \frac{1}{2} m_2 \dot{y}_2^2$$

$$T = \frac{1}{2} m_1 \dot{y}_1^2 + \frac{1}{2} m_2 \dot{y}_1^2$$

$$= \frac{1}{2} (m_1 + m_2) \dot{y}_1^2$$

$$y_2 = l - y_1$$

$$\rho = l - (y_1 + y_2)$$

$$\begin{aligned} U &= -m_1 g y_1 - m_2 g y_2 \\ &= -m_1 g y_1 - m_2 g (l - y_1) \\ &= -(m_1 - m_2) g y_1 - \underbrace{m_2 g l}_{\text{const}} \end{aligned}$$

$$y_1 + y_2 = l$$

$$y_2 = l - y_1$$

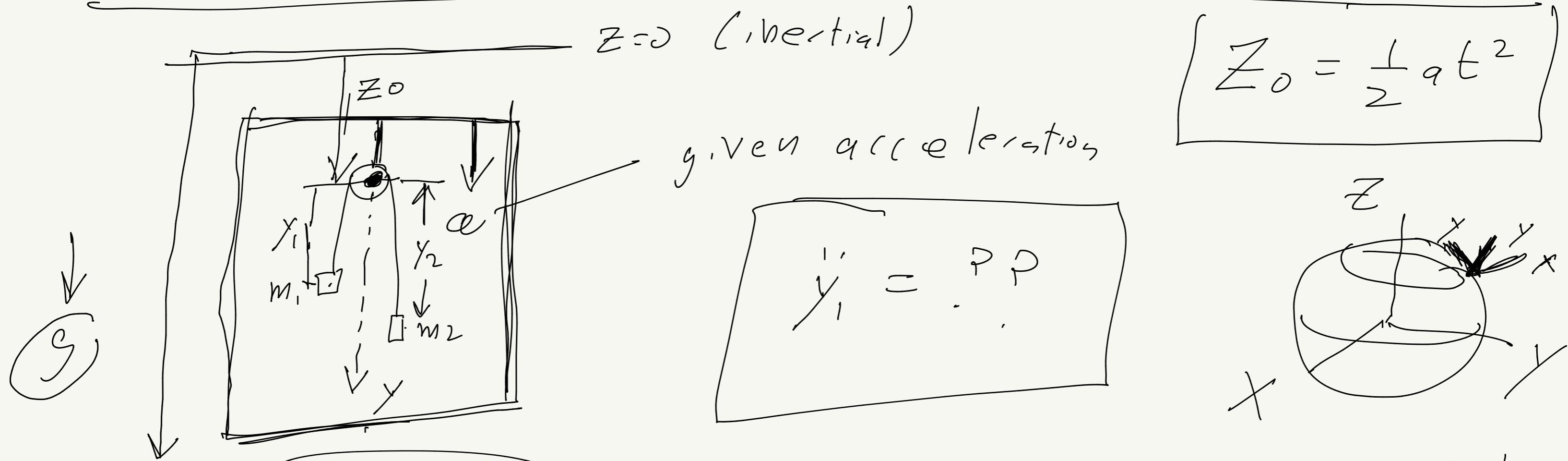
$$L = \frac{1}{2} (m_1 + m_2) \dot{y}_1^2 + (m_1 - m_2) g y_1$$

$$\ddot{y}_2 = -\ddot{y}_1$$

$$\frac{d}{dt} \left(\frac{\partial L}{\partial \dot{y}_1} \right) = \frac{\partial L}{\partial y_1} \rightarrow (m_1 + m_2) \ddot{y}_1 = (m_1 - m_2) g$$

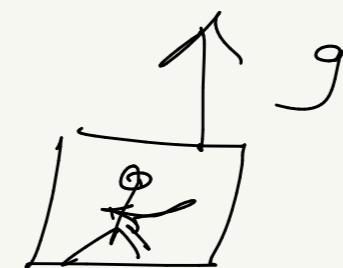
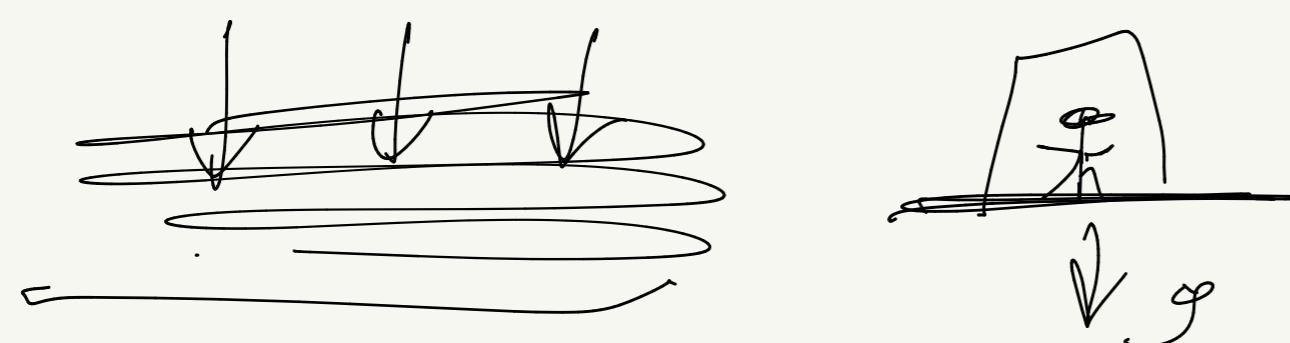
$$\ddot{y}_1 = \frac{(m_1 - m_2) g}{m_1 + m_2}$$

Analyze Atwood's machine in an accelerating reference frame.



Z $L = T - U$ is valid only wrt an inertial reference frame

$$\vec{F} = m \vec{a} \quad (\text{only wrt inertial frame})$$



Lec #9: Sep 21st

$$\vec{F} = m\vec{a} \quad (\text{Valid only wrt an inertial Frame})$$

$$\vec{F} + \underbrace{\vec{F}_{\text{fictitious}}}_{\text{coriolis Force } \leftarrow \\ + \text{centrifugal Force } \leftarrow \\ + \text{linear acceleration} \\ + \text{angular acceleration}} = m\vec{a}$$

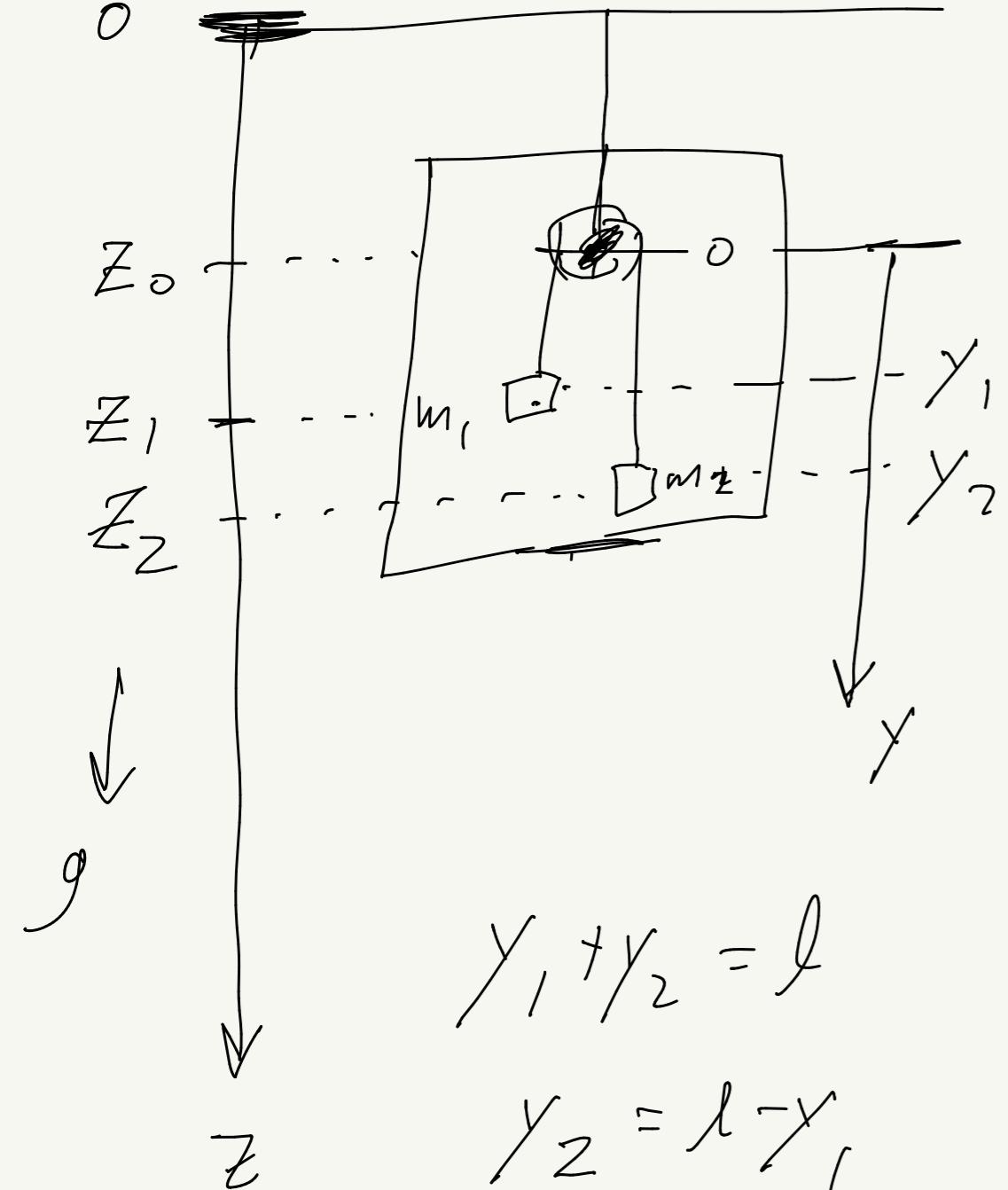
wrt a non-inertial frame

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-
-
-

$$\frac{d}{dt} \left(\frac{\partial L}{\partial \dot{q}_i} \right) = \frac{\partial L}{\partial q_i} \quad \begin{array}{l} \text{same form of EOMs} \\ \text{in inertial and non-inertial} \\ \text{ref frames} \end{array}$$

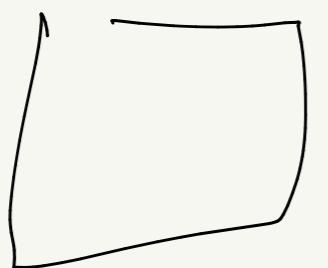
$$L = T - V \quad \text{Valid only in an inertial frame}$$

(Inertial Frame)



$$y_1 + y_2 = l$$

$$y_2 = l - y_1$$



$$L = T - V$$

wrt inertial frame

$$Z_1 = z_0 + y_1$$

$$Z_2 = z_0 + y_2$$

$$z_0 = \frac{1}{2} a t^2$$

unif acc \circ lent,

$$\begin{aligned} T &= \frac{1}{2} m_1 \dot{z}_1^2 + \frac{1}{2} m_2 \dot{z}_2^2 \\ &= \frac{1}{2} m_1 (\dot{y}_1^2 + a^2 t^2 + 2 a t \dot{y}_1) \\ &\quad + \frac{1}{2} m_2 (\dot{y}_2^2 + a^2 t^2 + 2 a t \dot{y}_2) \quad \left| \begin{array}{l} \dot{z}_1 = z_0 + \dot{y}_1 \\ \cdot = a t + \dot{y}_1 \\ z_2 = a t + \dot{y}_2 \end{array} \right. \\ &= \left(\frac{1}{2} m_1 \dot{y}_1^2 + \frac{1}{2} m_2 \dot{y}_2^2 \right) + \frac{1}{2} (m_1 + m_2) a^2 t^2 \\ &\quad + a t (m_1 \dot{y}_1 + m_2 \dot{y}_2) \end{aligned}$$

$$= \frac{d}{dt} (a t (m_1 \dot{y}_1 + m_2 \dot{y}_2)) = a (m_1 \dot{y}_1 + m_2 \dot{y}_2)$$

$$\boxed{T = \frac{1}{2} m_1 \dot{y}_1^2 + \frac{1}{2} m_2 \dot{y}_2^2 - a (m_1 \dot{y}_1 + m_2 \dot{y}_2)}$$

(ignore)
prescr.
function
of time

$$T = \frac{1}{2}m_1\dot{y}_1^2 + \frac{1}{2}m_2\dot{y}_2^2 - \alpha(m_1y_1 + m_2y_2)$$

$$y_2 = \ell y_1 \quad \rightarrow \quad \dot{y}_2 = \ell \dot{y}_1$$

$$\boxed{T = \frac{1}{2}(m_1 + m_2)\dot{y}_1^2 - \alpha(m_1y_1 + m_2\ell - m_2y_1)}$$

$$= \frac{1}{2}(m_1 + m_2)\dot{y}_1^2 - \alpha(m_1 - m_2)y_1 \quad \underbrace{- \alpha m_2 \ell}_{\text{ignore}}$$

$$\boxed{U = -m_1g z_1 - m_2g z_2}$$

$$= -m_1g(z_0 + y_1) - m_2g(z_0 + y_2)$$

$$= -m_1g y_1 - m_2g y_2 \quad \underbrace{-(m_1 + m_2)g z_0}_{\text{ignore}}$$

$$= -(m_1 - m_2)g y_1 \quad \underbrace{- m_2 g \ell}_{\text{ignore}} \quad \underbrace{\text{ignore}}_{\text{ignore}}$$

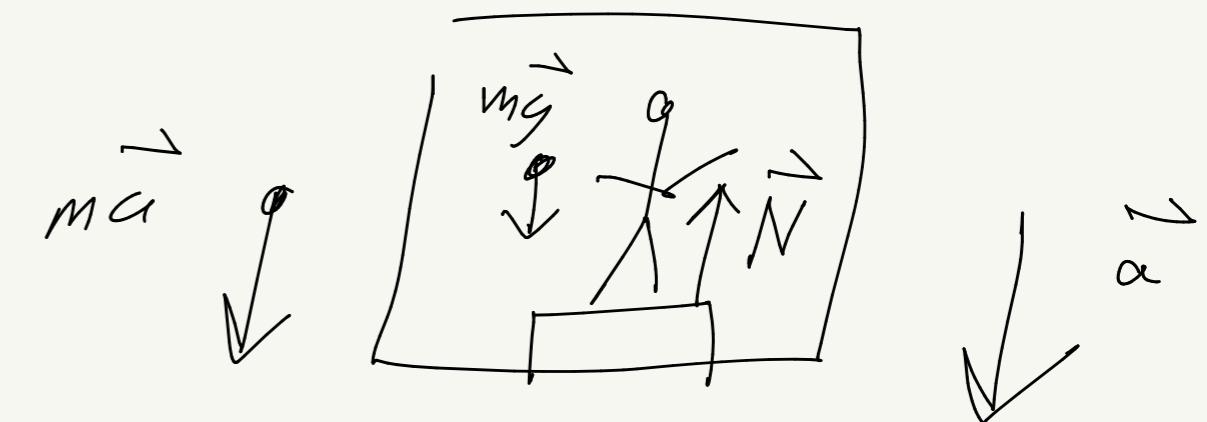
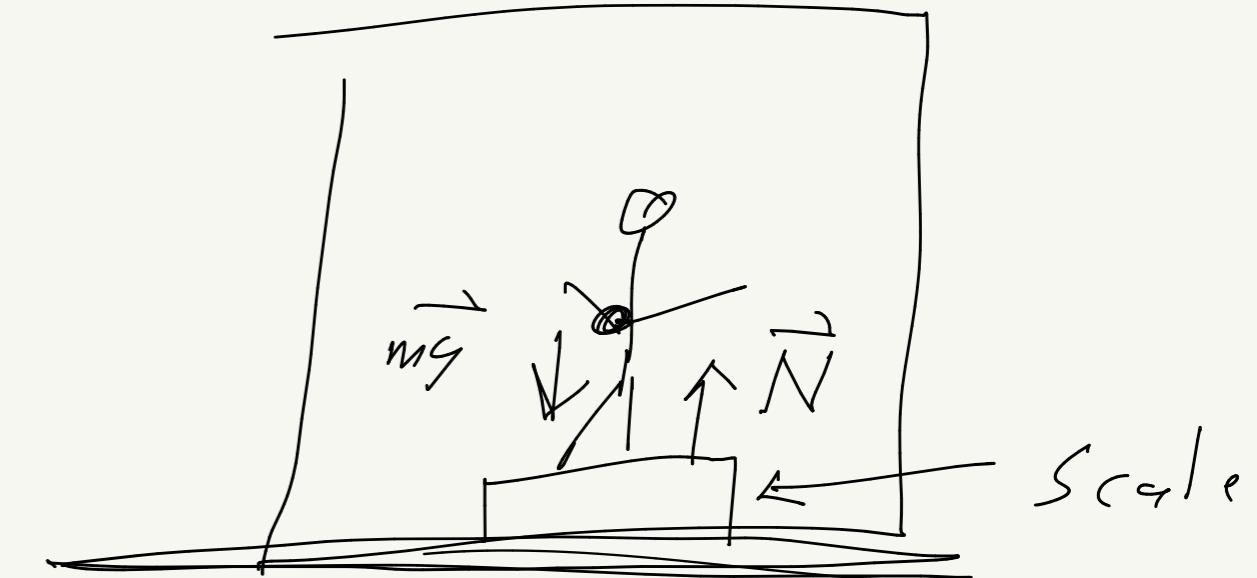
$$\boxed{D = T - U = \frac{1}{2}(m_1 + m_2)\dot{y}_1^2 - \alpha(m_1 - m_2)y_1 + (m_1 - m_2)g y_1}$$

$$= \frac{1}{2}(m_1 + m_2)\dot{y}_1^2 + (m_1 - m_2)(g - \alpha)y_1$$

$$\frac{d}{dt} \left(\frac{\partial L}{\partial \dot{y}_i} \right) = \frac{\partial L}{\partial y_i}$$

$$(m_1 + m_2) \ddot{y}_i = (m_1 - m_2)(g - a)$$

$$\rightarrow \boxed{\ddot{y}_i = \left(\frac{m_1 - m_2}{m_1 + m_2} \right) (g - a)}$$



$$m \vec{a}^1 = \vec{F}^1 \\ = \vec{m g}^1 + \vec{N}^1$$

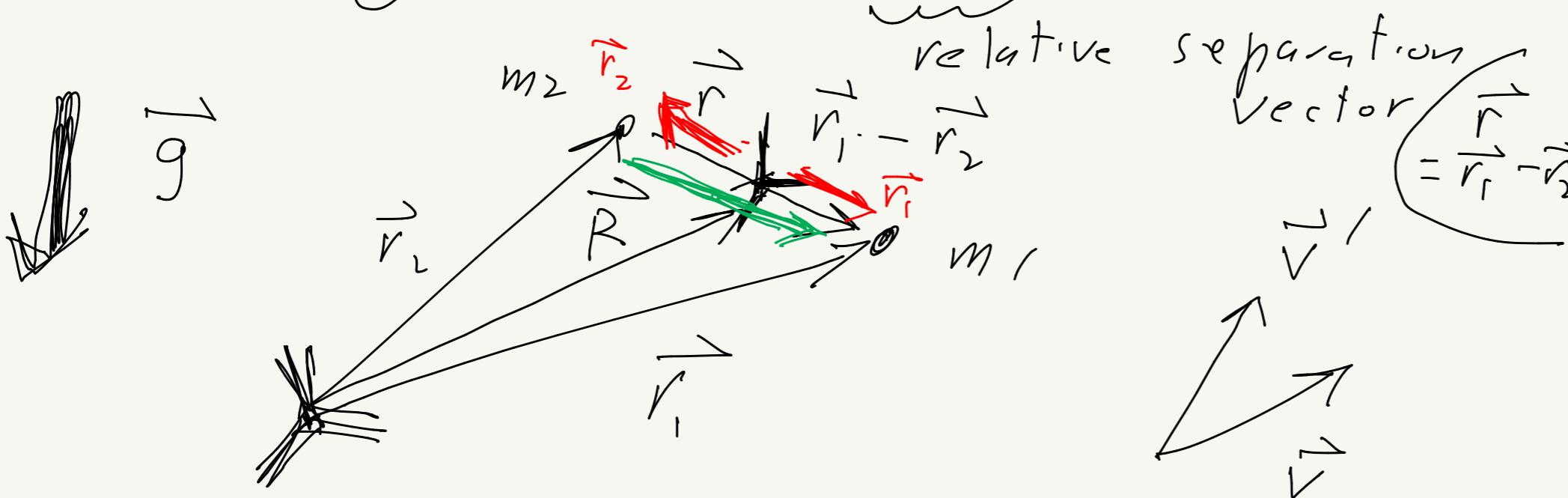
$$\vec{N}^1 = -m(\vec{g}^1 - \vec{a}^1)$$

$$\vec{N}^1 = 0 \quad \text{if } \vec{a}^1 = \vec{g}^1$$

Central force motion:

Two masses, closed system, interact via a central potential

$$U = U(|\vec{r}_1 - \vec{r}_2|)$$



e.g. $U = \frac{1}{2} \pi r^2$

$$U = -\frac{G m_1 m_2}{r}$$

$$r = |\vec{r}_1 - \vec{r}_2|$$

sphere oscillation

$t \rightarrow t + \delta t$

$$L = T - U$$

$$= \frac{1}{2} m_1 |\vec{r}_1|^2 + \frac{1}{2} m_2 |\vec{r}_2|^2 - U(|\vec{r}_1 - \vec{r}_2|)$$

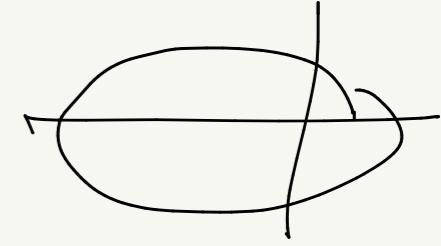
(1) no explicit time dependence $\Rightarrow E = T + U = \text{const}$

(2) fractional invariance $\vec{r}_a \rightarrow \vec{r}_a + \delta x : \vec{p} = \sum_a m_a \vec{v}_a = \text{const}$

(3) rotational invariance : $\vec{M} = \sum_a \vec{r}_a \times \vec{p}_a = \text{const}$

$$\left(\begin{array}{l} \vec{r}_a \rightarrow \vec{r}_a + \delta \phi \times \vec{r}_a \\ \vec{v}_a \rightarrow \vec{v}_a + \delta \phi \times \vec{v}_a \end{array} \right) \quad \left. \begin{array}{l} L + \delta L \\ L' \end{array} \right.$$

$$\begin{aligned} \vec{M} &= (\vec{r}_1 \times \vec{p}_1) + (\vec{r}_2 \times \vec{p}_2) \\ O = \dot{\vec{M}} &= \vec{v}_1 \times \vec{p}_1 + \vec{r}_1 \times \dot{\vec{p}}_1 + \vec{v}_2 \times \vec{p}_2 + \vec{r}_2 \times \dot{\vec{p}}_2 \\ \vec{p}_1 &= m_1 \vec{v}_1 \\ &= \vec{r}_1 \times \dot{\vec{p}}_1 + \vec{r}_2 \times \dot{\vec{p}}_2 \end{aligned}$$



two-body

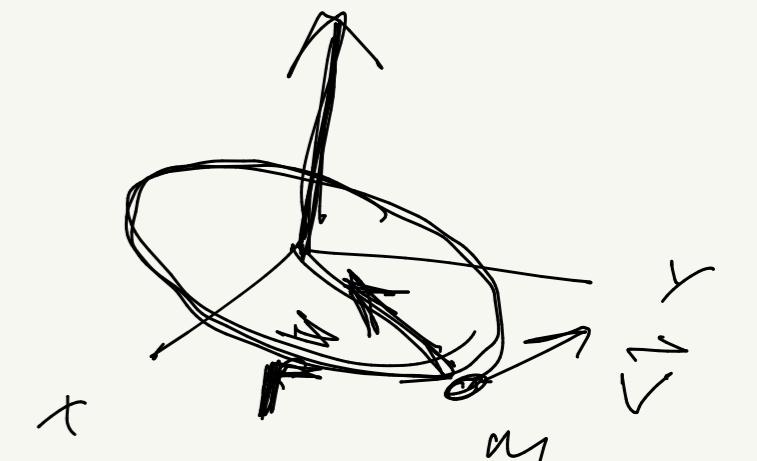
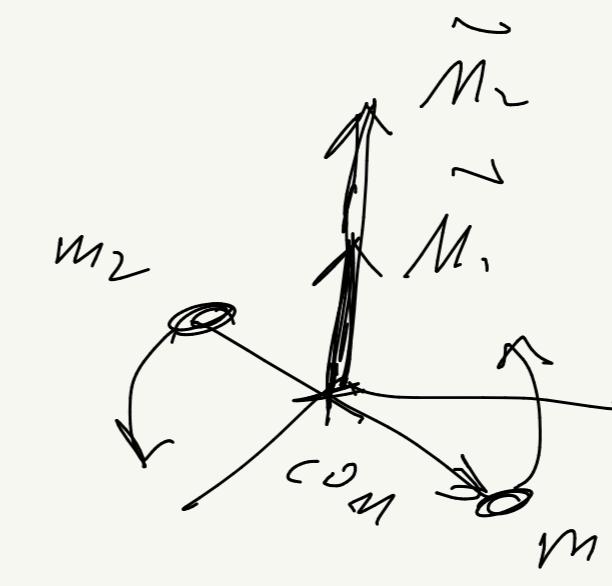
$$\vec{M}$$

$$\vec{M} = \vec{M}_1 + \vec{M}_2$$

$$\vec{P} = \vec{p}_1 + \vec{p}_2$$

$$= m_1 \vec{v}_1 + m_2 \vec{v}_2$$

$$\vec{p}_1 = 0$$

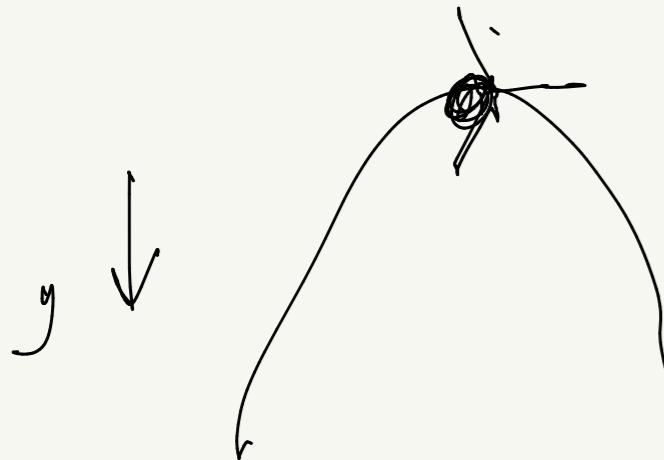


$$\vec{M} = m \vec{r} \times \vec{v}$$

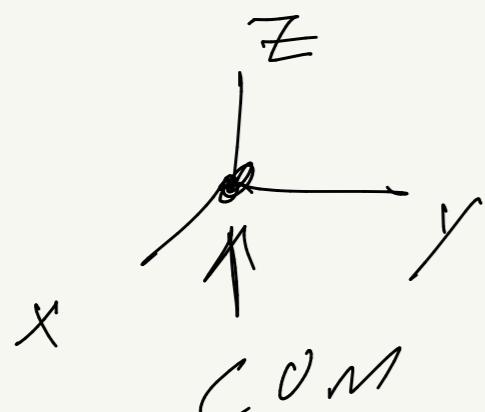
$$\begin{aligned} O = \dot{\vec{M}} &= m \vec{r} \times \dot{\vec{v}} + m \vec{r} \times \vec{v} \\ O &= m \vec{r} \times \vec{\omega} \end{aligned}$$

$\vec{P} = \text{const}$, i.e. com moves with const. vel. of \vec{R}

$$\begin{aligned}\vec{P} &= m_1 \vec{v}_1 + m_2 \vec{v}_2 = m_1 \vec{r}_1' + m_2 \vec{r}_2' \\ &= \frac{d}{dt} \left(\underbrace{\frac{m_1 \vec{r}_1 + m_2 \vec{r}_2}{m_1 + m_2}}_{\vec{R}} \right) \cdot (m_1 + m_2) \\ &= (m_1 + m_2) \boxed{\frac{d\vec{R}}{dt}}\end{aligned}$$



We can go to the COM Frame.



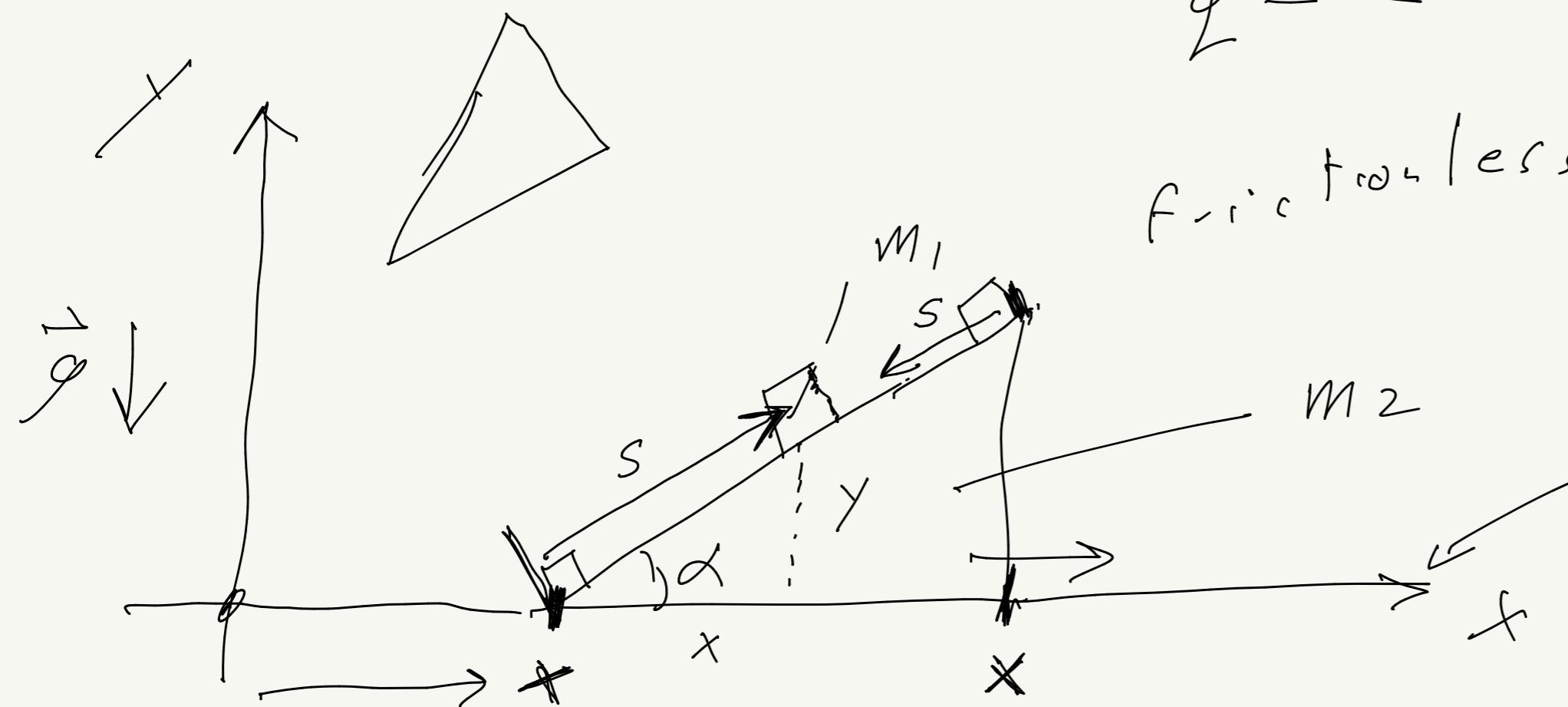
$$\boxed{\begin{array}{l} m_1 \vec{r}_1 + m_2 \vec{r}_2 = 0 \\ \vec{r} = \vec{r}_1 - \vec{r}_2 \end{array}}$$

$$\begin{aligned} \vec{P} &= 0 \\ \frac{d\vec{R}}{dt} &= 0 \\ \vec{R} &= \text{const} \\ &= \text{const} \\ &\text{Orig}\end{aligned}$$

QUIZ #2:

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qz - Firstname - lastname . pdf



Frictionless

~~String~~

$$\tan \alpha = \frac{y}{x}$$

Frictionless

1) Write down Lagrangian in terms of generalized coord)

2) what quantities (if any) are conserved?
why?

$$T = \frac{1}{2} m_1 (\dot{x}_1^2 + \dot{y}_1^2) + \frac{1}{2} m_2 (\dot{x}_2^2 + \dot{y}_2^2)$$

$$\left. \begin{array}{l} x_2 = x \\ y_2 = 0 \\ x_1 = x + s \cos \alpha \\ y_1 = s \sin \alpha \end{array} \right\}$$

Lec #10: (Th 9/23)

Midterm 1: Tues Oct 5th

Q2: $\dot{x}_1 = \dot{x} + s \cos \alpha$

$$\dot{y}_1 = s \sin \alpha$$

$$\dot{x}_2 = \dot{x}$$

$$\dot{y}_2 = 0$$

$$x_1 = x + s \cos \alpha$$

$$T = \frac{1}{2} m_1 \left(\underline{\dot{x}^2} + s^2 \underline{\cos^2 \alpha} + 2 \dot{x} s \cos \alpha \right) + s^2 \underline{\sin^2 \alpha}$$

$$+ \frac{1}{2} m_2 \underline{\dot{x}^2}$$

$$= \frac{1}{2} (m_1 + m_2) \dot{x}^2 + \frac{1}{2} m_1 s^2 + m_1 \dot{x} s \cos \alpha$$

$$U = m_1 g y_1 = m_1 g s \sin \alpha$$

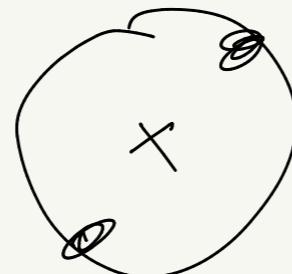
$$L = T - U, \quad E = T + U \text{ conserved (no explicit } t \text{ dependence)}$$

$$\frac{\partial L}{\partial x} = 0 \rightarrow \frac{\partial L}{\partial \dot{x}} = P_x \text{ conserved (no } x \text{ dependence)}$$

$$\text{CON: } m_1 \vec{r}_1 + m_2 \vec{r}_2 = 0 \quad (1)$$

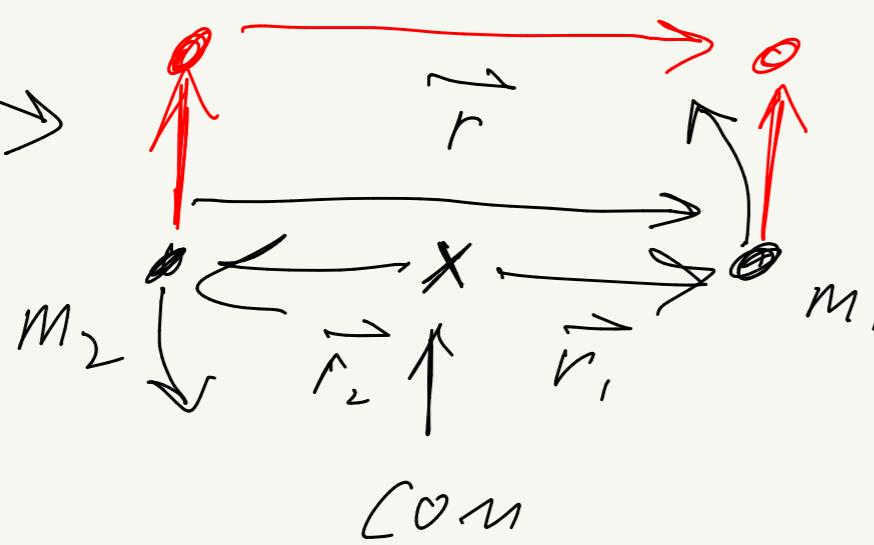
$$\vec{r}_1 - \vec{r}_2 = \vec{r} \quad (2)$$

$$\vec{r} = \vec{r}_1 - \vec{r}_2$$



$$\vec{r} \neq 0$$

for
rotational
motion



$$\vec{r}_2 = \vec{r}_1 - \vec{r}$$

$$m_1 \vec{r}_1 + m_2 (\vec{r}_1 - \vec{r}) = 0$$

$$(m_1 + m_2) \vec{r}_1 - m_2 \vec{r} = 0$$

$$\vec{r}_1 = \left(\frac{m_2}{m_1 + m_2} \right) \vec{r}$$

$$\vec{r}_2 = - \left(\frac{m_1}{m_1 + m_2} \right) \vec{r}$$

in
COM
Frame

$$\vec{r}_1 = \left(\frac{m_2}{m_1 + m_2} \right) \vec{r}, \quad \vec{r}_2 = - \left(\frac{m_1}{m_1 + m_2} \right) \vec{r}$$

$$T = \frac{1}{2} m_1 |\vec{r}_1|^2 + \frac{1}{2} m_2 |\vec{r}_2|^2$$

$$= \frac{1}{2} m |\vec{r}|^2$$

$$= 0 \text{ in COM frame}$$

$$m = \frac{m_1 m_2}{m_1 + m_2}$$

define

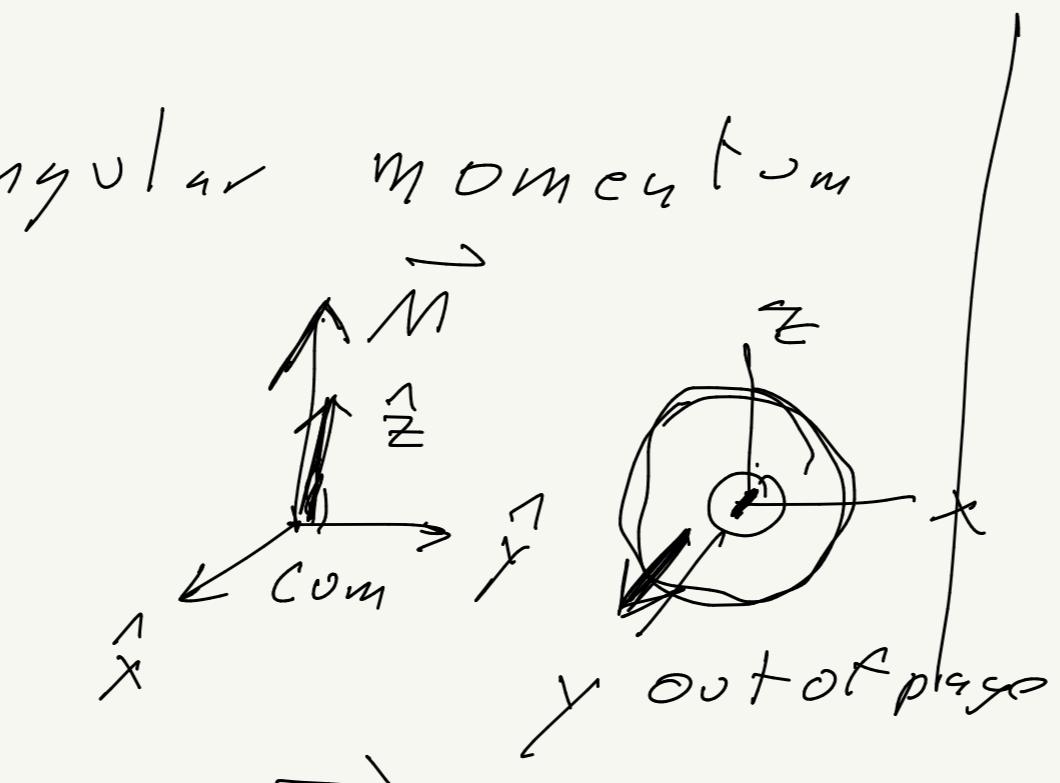
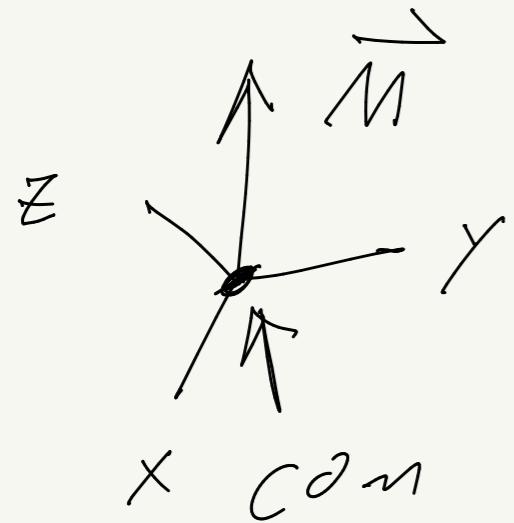
reduced
mass
of
system

$$U = U(|\vec{r}_1 - \vec{r}_2|) = U(|\vec{r}|) = U(r)$$

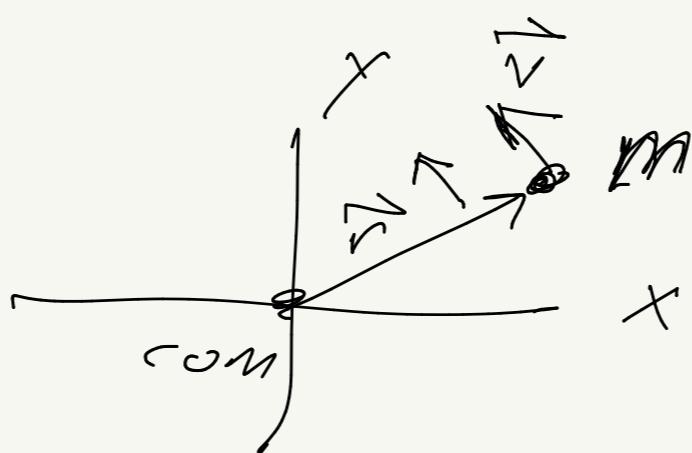
$$\boxed{F = T - U = \frac{1}{2}m|\vec{r}|^2 - U(r)}$$

(effective
one-body problem)

i) cons. of angular momentum



\vec{M} must lie in the xy plane



$$\begin{aligned} \vec{M} &= \text{const} \\ &= m_1 \vec{r}_1 \times \vec{v}_1 + m_2 \vec{r}_2 \times \vec{v}_2 \\ &= m \vec{r} \times \vec{v} \end{aligned}$$

$$\vec{r} = \vec{r}_1 - \vec{r}_2$$

$$\begin{aligned}
 L &= \frac{1}{2} m |\vec{r}|^2 - U(r) \\
 \cancel{\Rightarrow} &= \frac{1}{2} m (r^2 + r^2 \dot{\phi}^2) - U(r) \\
 &\quad \underbrace{\qquad\qquad}_{\dot{x}^2 + \dot{y}^2}
 \end{aligned}
 \quad \left| \begin{array}{l} \text{using polar coordinates} \\ (\vec{r}, \phi) \end{array} \right.$$

$$\frac{\partial L}{\partial \dot{\phi}} = 0 \quad \Rightarrow \quad \frac{\partial L}{\partial \dot{\phi}} = \text{const} = mr^2 \dot{\phi}$$

$M_z = mr^2 \dot{\phi}$

$\cancel{\qquad\qquad\qquad}$

$$\underline{M} = \underline{M}_z$$

not
to be
mis

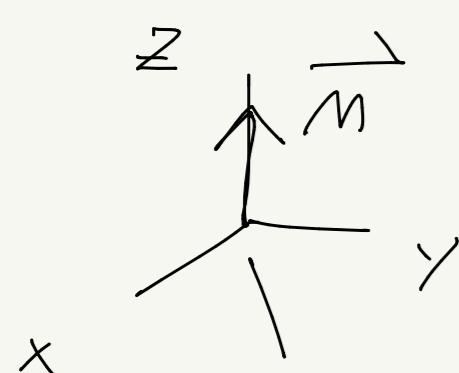
magnitude
of angular
vector \vec{M} ,
momentum

$$\frac{d \vec{M}}{dt} = 0$$

i) const. of linear momentum \rightarrow COM Frame

$$L = \sum m |\vec{r}_i|^2 - U(r) \quad \vec{r} = \vec{r}_1 - \vec{r}_2 \\ m = \frac{m_1 m_2}{m_1 + m_2}$$

ii) const. of angular momentum \rightarrow chose \vec{z} -axis to point along \vec{M}



$$\vec{M} = \vec{r} \times \vec{p} \\ = m \vec{r} \times \vec{r}$$

\rightarrow motion (\vec{r}, \vec{r}) lies in the $X-Y$ plane

com Using plane-polar coord (r, ϕ) :

$$L = \sum m (r^2 \dot{\phi}^2 + r^2 \dot{r}^2) - U(r)$$

$$\frac{\partial L}{\partial \dot{\phi}} = 0 \quad \rightarrow$$

$$\frac{\partial L}{\partial \dot{\phi}} = \text{const}$$

$$mr^2 \dot{\phi} = M_z$$

$$\dot{\phi} = \frac{M_z}{mr^2}$$

$$p_\phi = M_z = M$$

iii) const. of energy $E = T + U = \text{const}$

$$E = \frac{1}{2} m \dot{r}^2 + \frac{1}{2} m r^2 \dot{\phi}^2 + U(r) = \frac{1}{2} m \dot{r}^2 + \left(\frac{M_z^2}{2mr^2} + U(r) \right)$$

\uparrow

$U_{\text{eff}}(r)$

$$\boxed{E = \frac{1}{2} m \dot{r}^2 + V_{eff}(r)} \quad \text{where} \quad V_{eff}(r) = U(r) + \frac{M_Z^2}{2mr^2}$$

$$E - V_{eff}(r) = \frac{1}{2} m \dot{r}^2$$

$$\pm \sqrt{\frac{2}{m} (E - V_{eff}(r))} = \dot{r} = \frac{dr}{dt}$$

$$\int dt = \pm \int \frac{dr}{\sqrt{\frac{2}{m} (E - V_{eff}(r))}}$$

$$\frac{dr}{dt} = \frac{dr}{d\phi} \frac{d\phi}{dt}$$

next page

$$\pm \sqrt{\frac{2}{m} (E - V_{eff}(r))} = \frac{dr}{d\phi} \frac{M_Z}{mr^2}$$

$$\boxed{t = \pm \int \frac{dr}{\sqrt{\frac{2}{m} (E - U(r)) - \frac{M_Z^2}{m^2 r^2}}} + \text{const}} \quad (14.6)$$

$L \& L$

$$\rightarrow t = t(r)$$

$$r = r(t)$$

$$\frac{d\phi}{dt} = \frac{M_Z}{mr^2} \rightarrow \int d\phi = \int \frac{M_Z}{mr^2(t)} dt$$

$$\rightarrow \phi = \int \frac{M_Z}{mr^2(t)} dt + \text{const}$$

$$\int d\phi = \int \frac{\pm M_2 dr/r^2}{\sqrt{\frac{2m}{r}(E - V(r)) - \frac{M_2^2}{r^2}}} \quad (14.7)$$

L & L

$$\phi = \pm M_2 \int \frac{dr/r^2}{\sqrt{\frac{2m}{r}(E - V(r)) - \frac{M_2^2}{r^2}}} + \text{const}$$

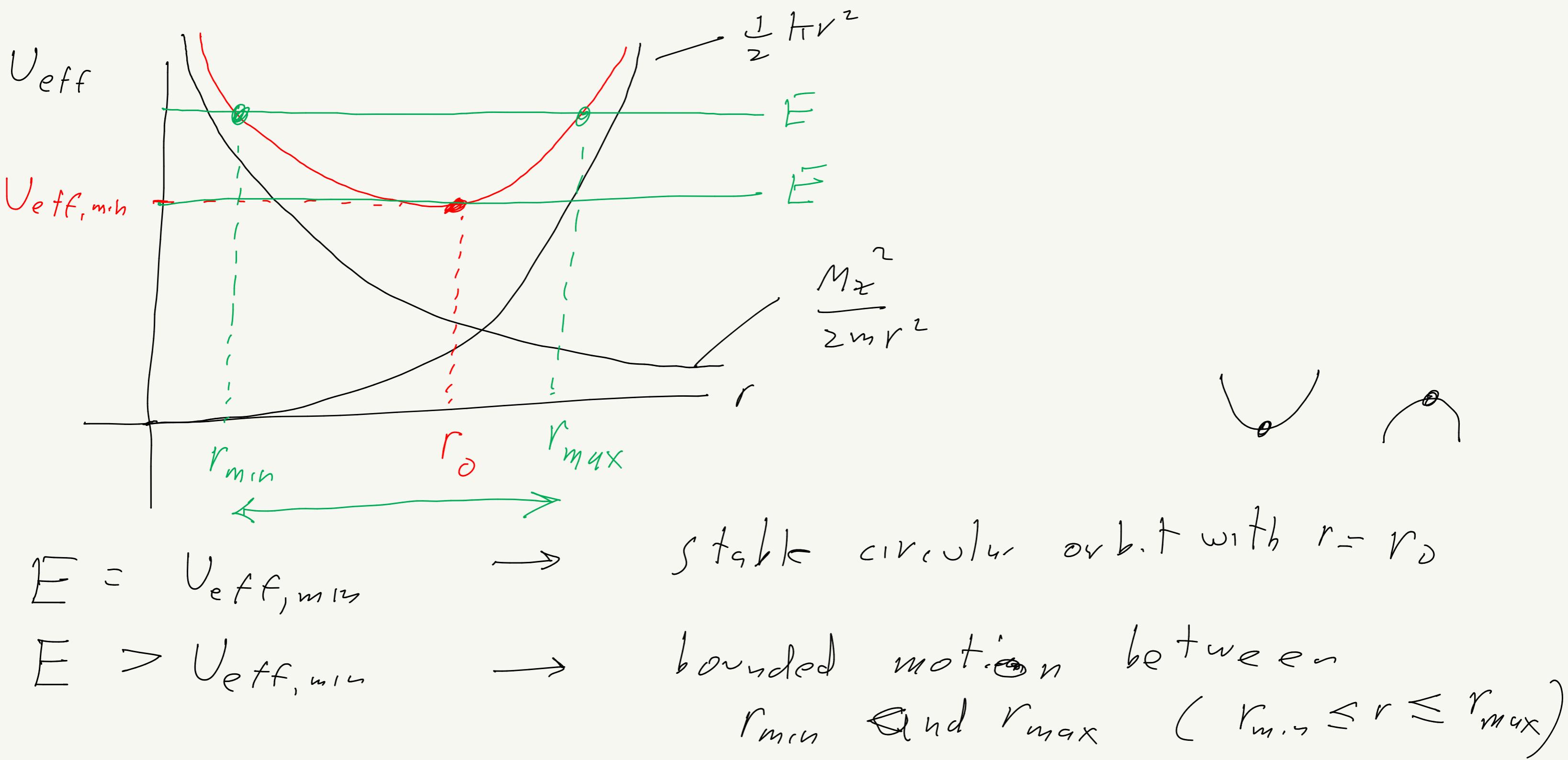
$$\phi = \phi(r) \iff r = r(\phi)$$

* * $V(r) = \frac{1}{2} kr^2$ (spring oscillator)

$$V(r) = -\frac{\alpha}{r} = -\frac{G m_1 m_2}{r}$$
 (Newtonian gravity)

$$U_{\text{eff}}(r) = U(r) + \frac{M_z^2}{2mr^2}$$

$$= \frac{1}{2} \frac{1}{r} r^2 + \frac{M_z^2}{2mr^2}$$



$$\phi = M_Z \int \frac{dr/r^2}{\sqrt{2m(E - V(r)) - \frac{M_Z^2}{r^2}}} + \text{const}$$

$$= M_Z \int \frac{dr/r^2}{\sqrt{2m(E - \frac{1}{2}mr^2) - \frac{M_Z^2}{r^2}}} + \text{const}$$

$$= M_Z \int \frac{\cancel{dr/r^2}}{\sqrt{2mE - mr^2 - M_Z^2/r^2}} + \text{const}$$

1

$$\sqrt{a + bx + cx^2} = \sqrt{a + b\theta + c\sin^2\theta} \quad \text{e.g.} \quad \int \frac{dx}{\sqrt{1-x^2}} = \sin^{-1}x + \cos\theta$$

$$\sin^{-1}x = \theta = \int d\theta \quad x = \sin\theta \quad \rightarrow \quad dx = (\cos\theta)d\theta$$

$$\sqrt{1 - \sin^2\theta} = \sqrt{1 - \sin^2\theta} = \cos\theta$$

$$u = \frac{1}{r} \quad \rightarrow \quad du = -\frac{1}{r^2} dr \quad \rightarrow \quad \frac{dr}{r^2} = -du$$

$$\sqrt{\quad} = \sqrt{2mE - \frac{m\Gamma}{u^2} - M_z^2 u^2}$$

$$= \frac{1}{u} \sqrt{2mEu^2 - m\Gamma - M_z^2 u^4}$$

$$\phi = -M_z \int \frac{u du}{\sqrt{2mEu^2 - m\Gamma - M_z^2 u^4}} + \text{const}$$

$$v = u^2$$

$$\rightarrow dv = 2u du \quad \rightarrow \quad u du = \frac{dv}{2}$$

$$\sqrt{\quad} = \sqrt{2mEv - m\Gamma - M_z^2 v^2}$$

$$\phi = -\frac{M_z}{2} \int \frac{dv}{\sqrt{2mEv - m\Gamma - M_z^2 v^2}} + \text{const}$$

Complete the square:

$$\overbrace{-M_Z^2 v^2 + 2mE v - mH}^{\uparrow} = -M_Z^2 \left(v^2 - \frac{2mE}{M_Z^2} v + \frac{mH}{M_Z^2} \right)$$

$$= -M_Z^2 \left(\left(v - \frac{mE}{M_Z^2} \right)^2 - \frac{m^2 E^2}{M_Z^2} + \frac{mH}{M_Z^2} \right)$$

$$= -M_Z^2 \left((v-A)^2 - B^2 \right)$$

$$= M_Z^2 \left(B^2 - (v-A)^2 \right)$$

$$A = \frac{mE}{M_Z^2}$$

$$B^2 = A^2 - \frac{mH}{M_Z^2}$$

$$E \geq V_{\text{eff, min}}$$

$$\phi = -\frac{1}{2} \int \frac{dv}{\sqrt{\frac{m^2}{2} (B^2 - (v-A)^2)}} + \text{const}$$

$\int \frac{dx}{\sqrt{1-x^2}} = \sin^{-1} x$

Let: $v-A = B \sin \theta$

$$dv = \underline{B \cos \theta d\theta}$$

↑

$$B^2 - (v-A)^2 = B^2 - B^2 \cos^2 \theta$$

$$= B^2 \sin^2 \theta$$

= $B \cos \theta$

$$\begin{aligned} \phi &= -\frac{1}{2} \int d\theta + \text{const} \\ &= -\frac{1}{2} \theta + \text{const} \\ &= -\frac{1}{2} \sin^{-1} \left(\frac{v-A}{B} \right) + \text{const} \\ &= -\frac{1}{2} \sin^{-1} \left(\frac{\sqrt{r^2 - A^2}}{B} \right) + \underline{\text{const}} \end{aligned}$$

$$\begin{aligned} v-A &\approx B \sin \theta \\ \sin \theta &= \frac{v-A}{B} \end{aligned}$$

$$\theta = \sin^{-1} \left(\frac{v-A}{B} \right)$$

$$\begin{aligned} v &= u^2 = \frac{1}{r^2} \\ u &= \frac{1}{r} \end{aligned}$$

Choose const so that $\dot{\phi} = 0 \iff r = r_{\max}$

$$\theta = -\frac{1}{2} \sin^{-1} \left(\frac{\frac{1}{r_{\max}^2} - A}{B} \right) + \text{const}$$

At a turning point ($r = r_{\min}$ or $r = r_{\max}$)

$$B^2 - (v - A)^2 = 0 \rightarrow v - A = \pm B$$

$$\begin{aligned} \frac{1}{r_{\min}^2}, \frac{1}{r_{\max}^2} &= A \pm B \\ \frac{1}{r_{\max}^2} &= A - B \\ \frac{1}{r_{\min}^2} &= A + B \end{aligned}$$

$$\begin{aligned} \theta &= -\frac{1}{2} \sin^{-1} \left(\frac{-B}{B} \right) + \text{const} \\ &= -\frac{1}{2} \sin^{-1}(-1) + \text{const} \\ &= -\frac{1}{2} \left(-\frac{\pi}{2} \right) + \text{const} \\ &= \frac{\pi}{4} + \text{const} \end{aligned}$$

$$\text{const} = -\frac{\pi}{4}$$

$$A = \frac{m E}{M_z^2}$$

$$B^2 = A^2 - \frac{m k}{M_z^2}$$

$$\phi = -\frac{1}{2} \operatorname{sgn}^{-1}\left(\frac{\frac{1}{r^2} - A}{B}\right) - \frac{\pi}{4}$$

$$\phi + \frac{\pi}{4} = -\frac{1}{2} \operatorname{sgn}^{-1}\left(\frac{\frac{1}{r^2} - A}{B}\right)$$

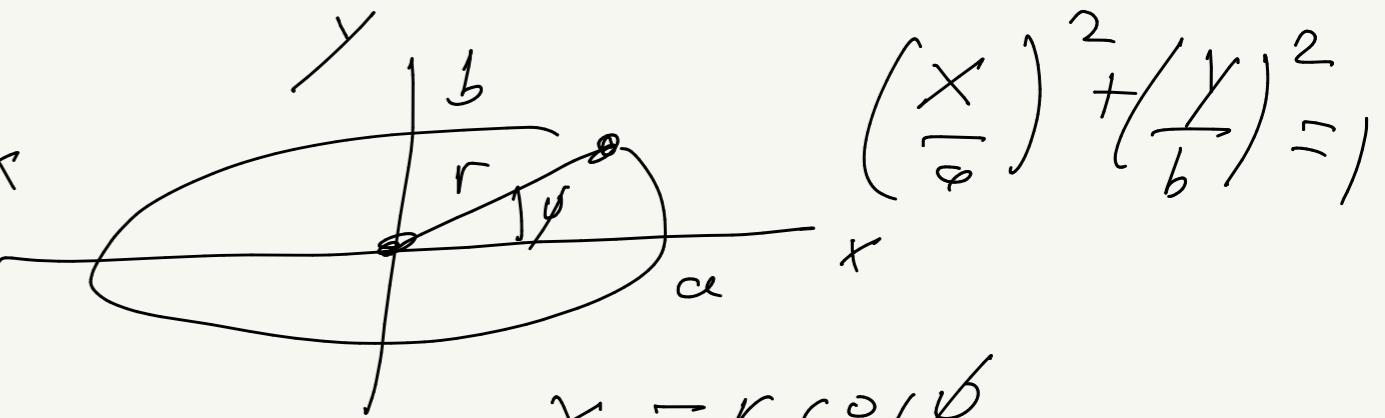
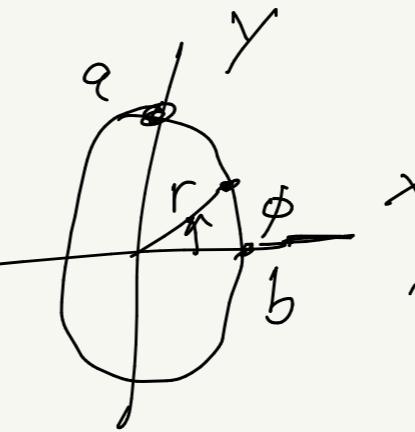
$$-\frac{1}{\pi} \operatorname{sgn}\left(2\left(\phi + \frac{\pi}{4}\right)\right) = \operatorname{sgn}^{-1}\left(\frac{\frac{1}{r^2} - A}{B}\right)$$

$$\rightarrow \operatorname{sgn}\left(2\left(\phi + \frac{\pi}{4}\right)\right) = \frac{\frac{1}{r^2} - A}{B}$$

$$\begin{aligned} & \operatorname{sgn}(-x) \\ & \approx -\operatorname{sgn} x \end{aligned}$$

$$\begin{aligned} LHS &= -\operatorname{sgn}\left(2\phi + \frac{\pi}{2}\right) \\ &= -\left(\operatorname{sgn}(2\phi) \underbrace{\cos\left(\frac{\pi}{2}\right)}_{=0} + \cancel{\cos(2\phi)} \operatorname{sgn}\left(\frac{\pi}{2}\right)\right) \\ &= -\cos 2\phi \end{aligned}$$

$$-I_{01} 2\phi = \frac{\frac{1}{r^2} - A}{B}$$



$$x = r \cos \phi$$

$$y = r \sin \phi$$

ellipse w. foci

center of ellipse
at origin

$$\boxed{\frac{1}{r^2} = A - B \cos 2\phi}$$

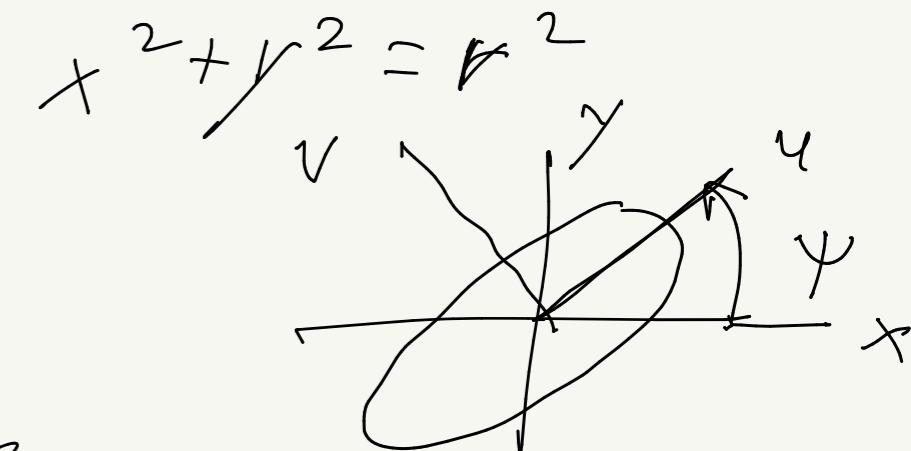
$$I = Ar^2 - Br^2 \underbrace{\cos 2\phi}_{\cos^2 \phi - \sin^2 \phi}$$

$$= Ar^2 - Br^2(\cos^2 \phi - \sin^2 \phi)$$

$$= A(x^2 + y^2) - B(x^2 - y^2)$$

$$= (A-B)x^2 + (A+B)y^2$$

$$= \left(\frac{x}{a}\right)^2 + \left(\frac{y}{b}\right)^2$$



~~alpha~~

$$\frac{1}{a^2} = A - B$$

$$\frac{1}{b^2} = A + B$$

$$a = \sqrt{\frac{1}{A-B}}, b = \sqrt{\frac{1}{A+B}}$$

Lec #11:

Tues 9/28

- Midterm #1, Tues, Oct 5th (In class,
8 short answer - 40%
2 longer problems - 60%)
|
Notify me if
you are not
feeling well
- Blackboard Zoom recordings
- i) deriving $t = t(r)$, $\phi = \phi(r)$ integrals
 - ii) solving for $\phi = \phi(r)$ for $U = \frac{1}{2} kr^2$
- Today
- i) clear up constant calculations
 - ii) complete square oscillator potential problem
- Thursday : Q&A

$$\frac{1}{a^2} = A - B \quad , \quad \frac{1}{b^2} = A + B$$

$$a^2 + b^2 = \frac{1}{A-B} + \frac{1}{A+B}$$

$$= \frac{A+B+A-B}{A^2-B^2}$$

$$= \frac{2A}{A^2-B^2} = \frac{2\cancel{\mu E/M_2}}{\cancel{\mu k/M_2}} = \frac{2E}{k}$$

$$\boxed{F = \frac{1}{2} k(a^2+b^2)} \quad \leftarrow$$

$$\frac{m}{M_2^2} = A^2 - B^2 = (A-B)(A+B)$$

$$= \frac{1}{c^2} \frac{1}{b^2}$$

$$\frac{m}{M_2^2} = \frac{1}{a^2 b^2}$$

$$\rightarrow \boxed{M_2 = \sqrt{m/k} ab}$$

$$\left. \begin{array}{l} A = \frac{m E}{M_2^2} \\ B^2 = A^2 - \frac{m k}{M_2^2} \end{array} \right\}$$

$$E = \frac{1}{2} k x_0^2$$

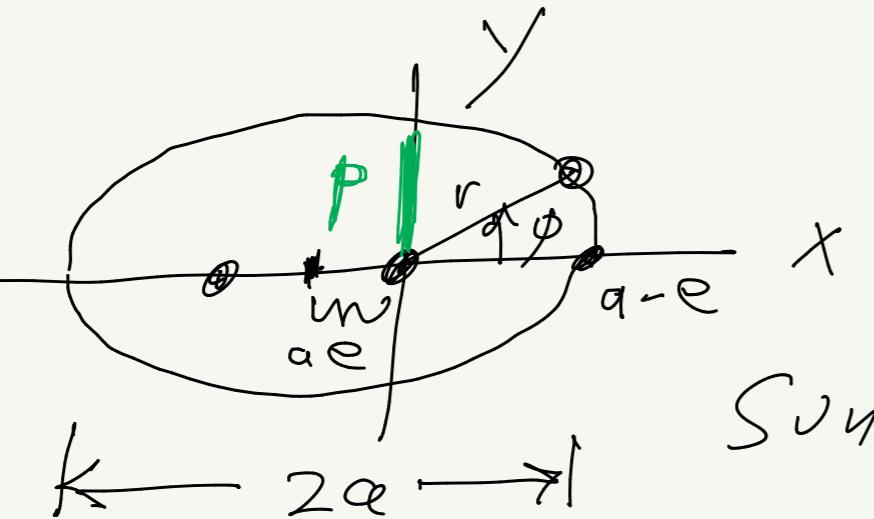
\uparrow
max displacement
with zero
initial velocity

$$U = -\frac{\alpha}{r} = -\frac{G m_1 m_2}{r}$$

~~(Kepler's Law)~~

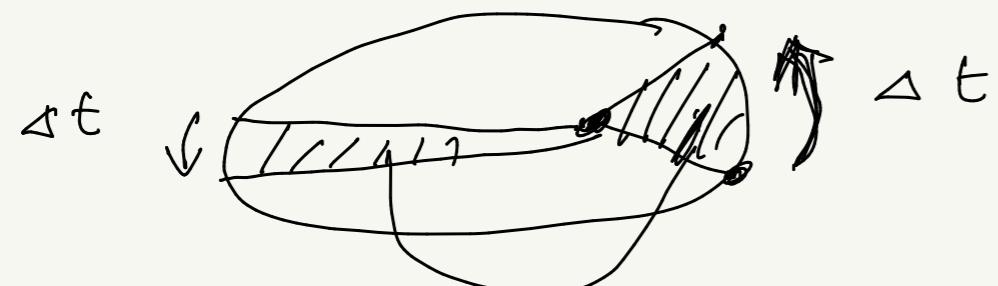
(1.)

$$E = -\frac{\alpha}{2a}$$



planet orbits
the Sun
in an
elliptical
orbit
with
Sun at focal point

(2) Equal areas in equal times



(3). area are equal

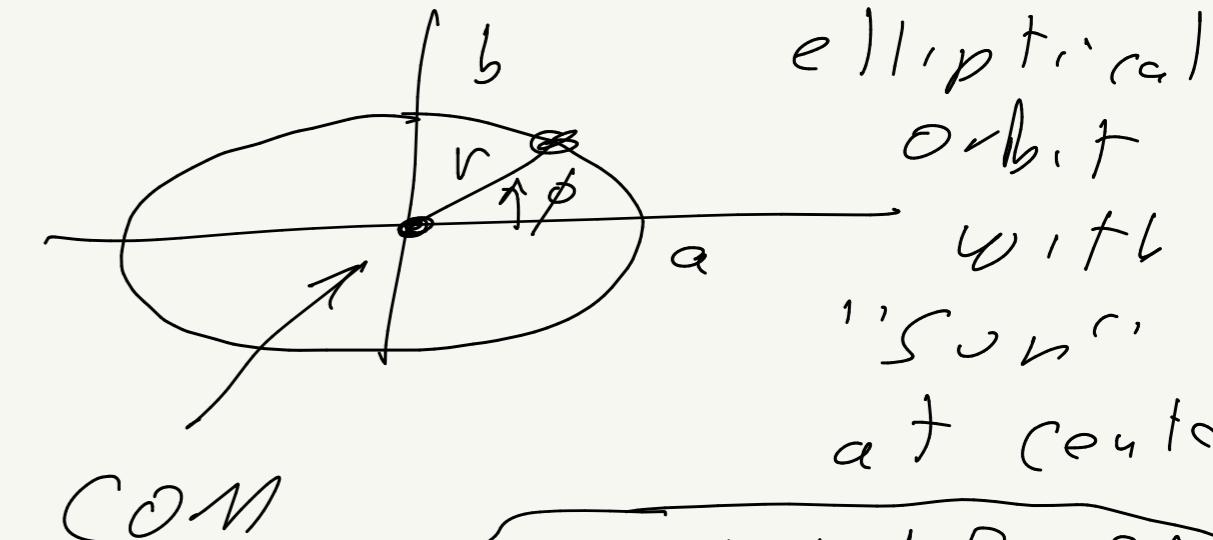
$$P^2 \propto a^3$$

$$\frac{P^2}{a^3} = \text{const}$$

period

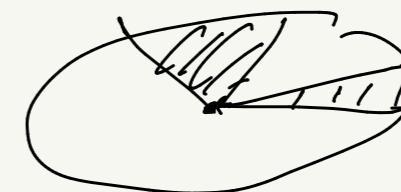
$$U = \frac{1}{2} k r^2$$

(1.) "Planet" moves around "Sun"
in an
elliptical
orbit



(2.) Equal areas
in equal time

$$E = \frac{1}{2} k (a^2 + b^2)$$

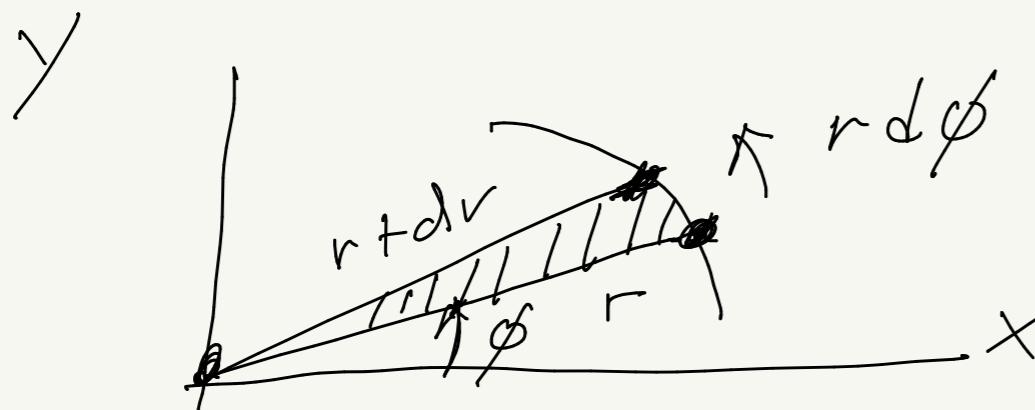


(3.) $P = \frac{2\pi}{\omega}, \omega \equiv \sqrt{\frac{k}{m}}$
irdep. of the
size of ellipse

a, b

a, e

φ, P



$$\begin{aligned} dA &= \frac{1}{2} \text{base} \cdot \text{height} \\ &\approx \frac{1}{2} r d\phi \cdot (r + dr) \\ &= \frac{1}{2} r^2 d\phi \quad + \frac{1}{2} r d\phi \cdot dr \end{aligned}$$

$$\begin{aligned} \dot{A}(t) &= \left(\frac{dA}{dt} \right) = \frac{1}{2} r^2 \frac{d\phi}{dt} \\ &= \frac{1}{2} r^2 \frac{M_2}{mr^2} \\ &= \frac{1}{2} \frac{M_2}{m} \\ &= \text{const} \end{aligned}$$

$$dA = \text{const} \cdot dt$$

$$\boxed{\frac{dA}{dt} = \frac{1}{2} \frac{M_2}{m}}$$

$$M_2 = mr^2 \dot{\phi} \rightarrow \dot{\phi} = \frac{M_2}{mr^2}$$

2nd
order
small
ignore

Equal areas \rightarrow
equal times \therefore
a consequence of
cons. of angular
momentum (hold,
for all central
potentials)

$$\frac{dA}{dt} = \frac{1}{2} \frac{M_2}{m}$$

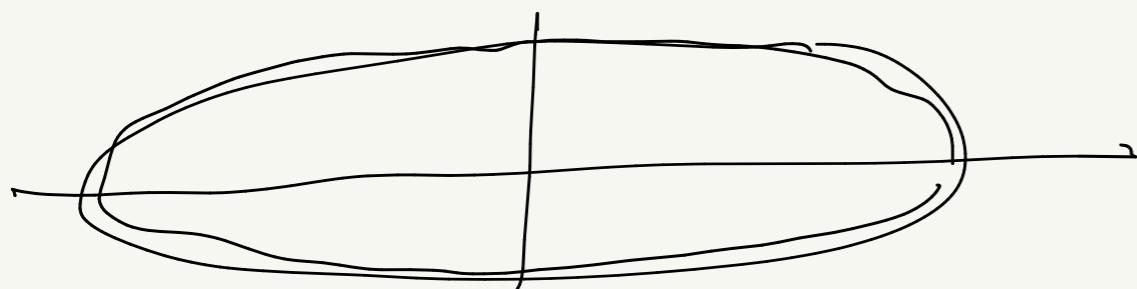
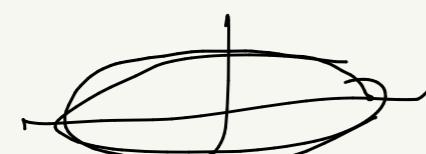
$$\int dA = \int \frac{1}{2} \frac{M_2}{m} dt$$

$$A = \frac{1}{2} \frac{M_2}{m} P$$

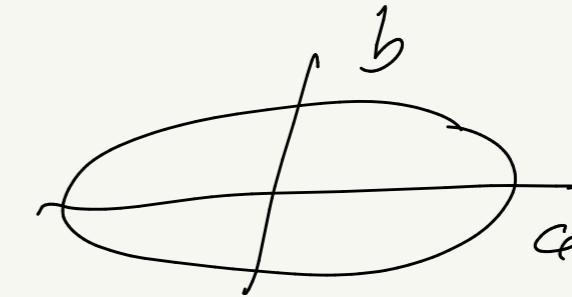
$$\pi_{ab} = \frac{1}{2} \frac{\sqrt{mP}}{m} ab P$$

$$\pi = \frac{1}{2} \sqrt{\frac{P}{m}} P$$

$$\boxed{\frac{2\pi}{\omega} = P}$$

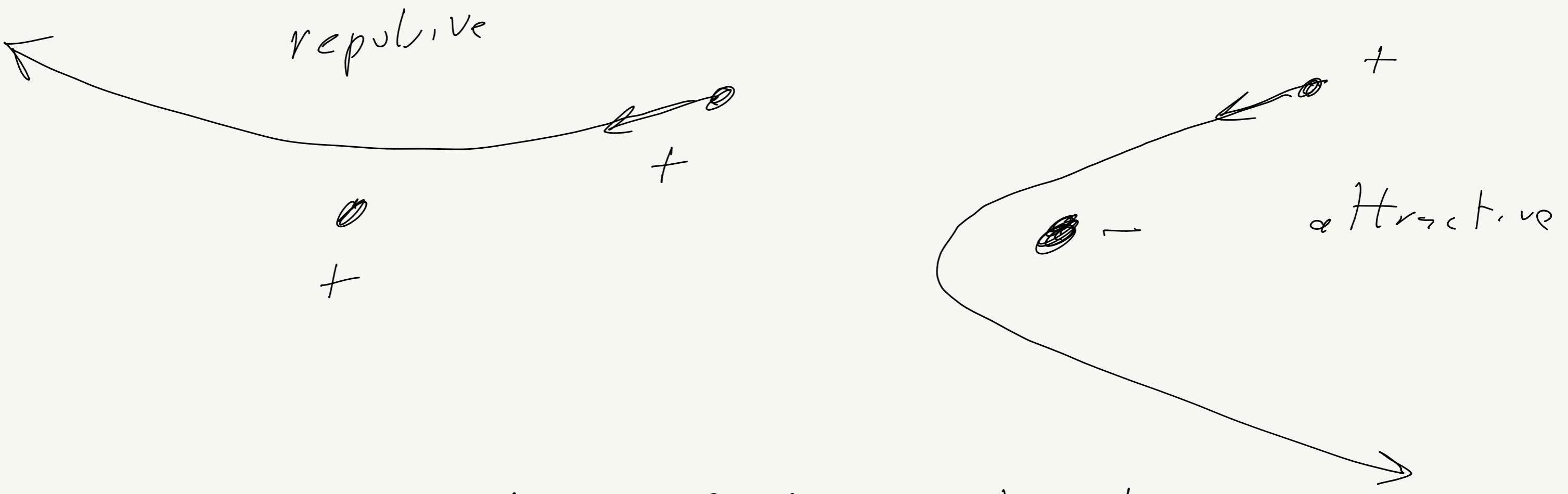


$$M_2 = \sqrt{mP} ab$$



$$\sqrt{\frac{P}{m}} = \omega$$

~~m_1~~ $\rightarrow m_2$
 $\cup (\vec{r}_1, \vec{r}_2)$
 $\cup (|\vec{r}_1 - \vec{r}_2|)$
~~cur. of angular momentum~~



Solving for $r = r(\epsilon)$, $\phi(\epsilon)$, $x(\epsilon)$, $V(\epsilon)$: (For $V = \frac{1}{2} k r^2$)

$$t = - \int \frac{dr}{\sqrt{\frac{2}{m} \left(E - \frac{1}{2} k r^2 \right) - \frac{M_\epsilon^2}{m^2 r^2}}} + C_1 t$$

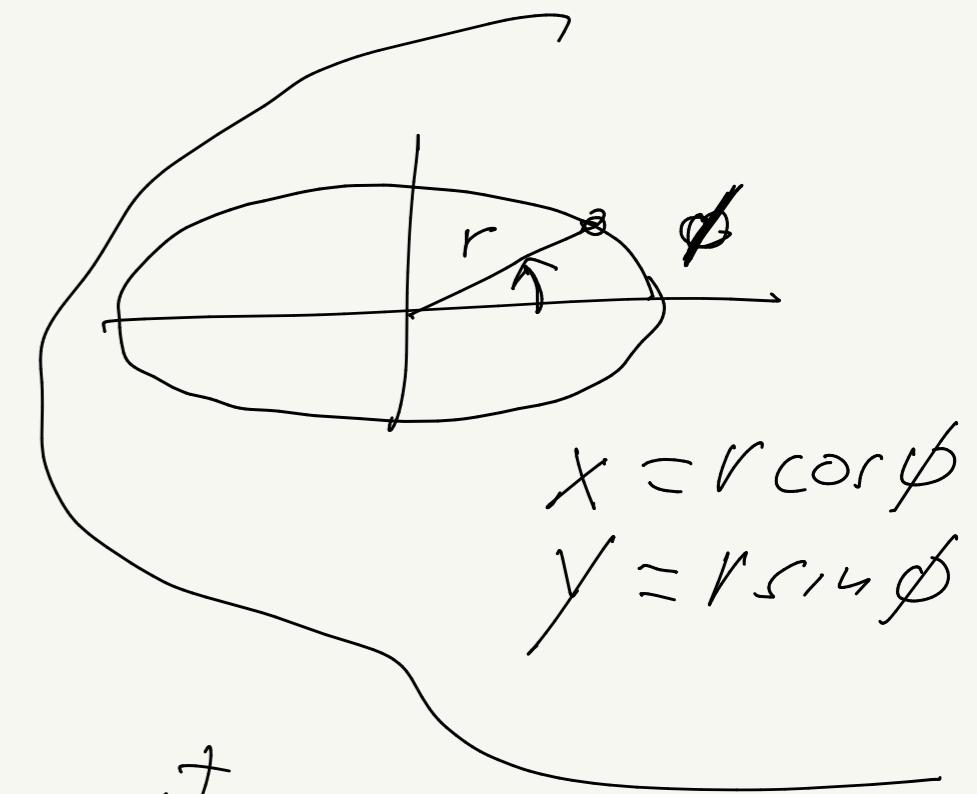
$$\begin{aligned} E &= \frac{1}{2} k (a^2 + b^2) \\ M_k &= \sqrt{m k} ab \end{aligned}$$

$$r = \frac{2}{m} \left(\frac{1}{2} k (a^2 + b^2) - \frac{1}{2} k r^2 \right) - \frac{m k a^2 b^2}{m^2 r^2}$$

$$= \frac{k}{m} \left(a^2 + b^2 - r^2 - \frac{a^2 b^2}{r^2} \right)$$

$$\sqrt{\phi} = \sqrt{\frac{1}{r^2} + \frac{k}{m}} \left(r^2(a^2+b^2) - r^4 - a^2b^2 \right)$$

$$= \frac{1}{r} \omega \sqrt{-(r^2-a^2)(r^2-b^2)}$$



$$\rightarrow t = - \int \frac{dr}{\frac{\omega}{r} \sqrt{-(r^2-a^2)(r^2-b^2)}} + \text{const}$$

$$\omega t = - \int \frac{r dr}{\sqrt{-(r^2-a^2)(r^2-b^2)}} + \text{const}$$

Let: $r^2 = a^2 \cos^2 \xi + b^2 \sin^2 \xi$

$$\oint r dr = \int a^2 \cos \xi (-\sin \xi) d\xi + \int b^2 \sin \xi \cos \xi d\xi$$

$$r dr = -(a^2 - b^2) \sin \xi \cos \xi d\xi$$

in numerator

$$r^2 = x^2 + y^2$$

$$x = a \cos \xi$$

$$y = b \sin \xi$$

parametric:
 $\xi \neq \phi$

$$-(r^2 - a^2)(r^2 - b^2) = (a^2 - b^2)^2 \sin^2 \xi \cos^2 \xi$$

~~Right angle~~



$$r^2 = a^2 \cos^2 \xi + b^2 \sin^2 \xi$$

$$r^2 - a^2 = a^2 (\underbrace{\cos^2 \xi - 1}_{}) + b^2 \sin^2 \xi$$

$$= -(a^2 - b^2) \sin^2 \xi$$

$$r^2 - b^2 = a^2 \cos^2 \xi + b^2 (\underbrace{\sin^2 \xi - 1}_{})$$

$$= (a^2 - b^2) \cos^2 \xi$$

$$\sqrt{ } = (a^2 - b^2) \sin \xi \cos \xi$$

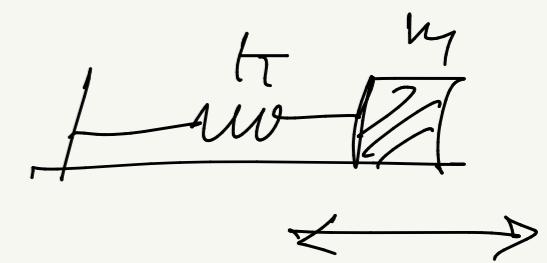
$$r dr = -(a^2 - b^2) \sin \xi \cos \xi d\xi$$

$$\rightarrow w t = + \int d\xi + \text{const}$$

$$w t = \xi + \text{const} \quad \begin{matrix} = 0 \\ \downarrow \end{matrix}$$

$$w t = \xi$$

$$r^2 = a^2 \cos^2(\omega t) + b^2 \sin^2(\omega t) \quad \leftarrow r = r(t)$$



$$= x^2 + y^2$$

$$\begin{cases} x = a \cos(\omega t) \\ y = b \sin(\omega t) \end{cases} \quad \leftarrow x(t), y(t)$$

$$\omega = \sqrt{\frac{k}{m}} = \text{const}$$

$$U = \frac{1}{2} k r^2$$

$$\begin{cases} x = r \cos \phi \\ y = r \sin \phi \end{cases} \quad \div \quad \tan \phi = \frac{y}{x} = \frac{b}{a} \tan(\omega t)$$

$$\phi = \arctan \left(\frac{b}{a} \tan(\omega t) \right) \quad \leftarrow \phi = \phi(t)$$

$$M_z = m r^2 \dot{\phi} = \sqrt{m k} a b$$

$$r^2 \dot{\phi} = \sqrt{\frac{k}{m}} a b$$

$$\dot{\phi} = \frac{\omega a b}{r^2}$$

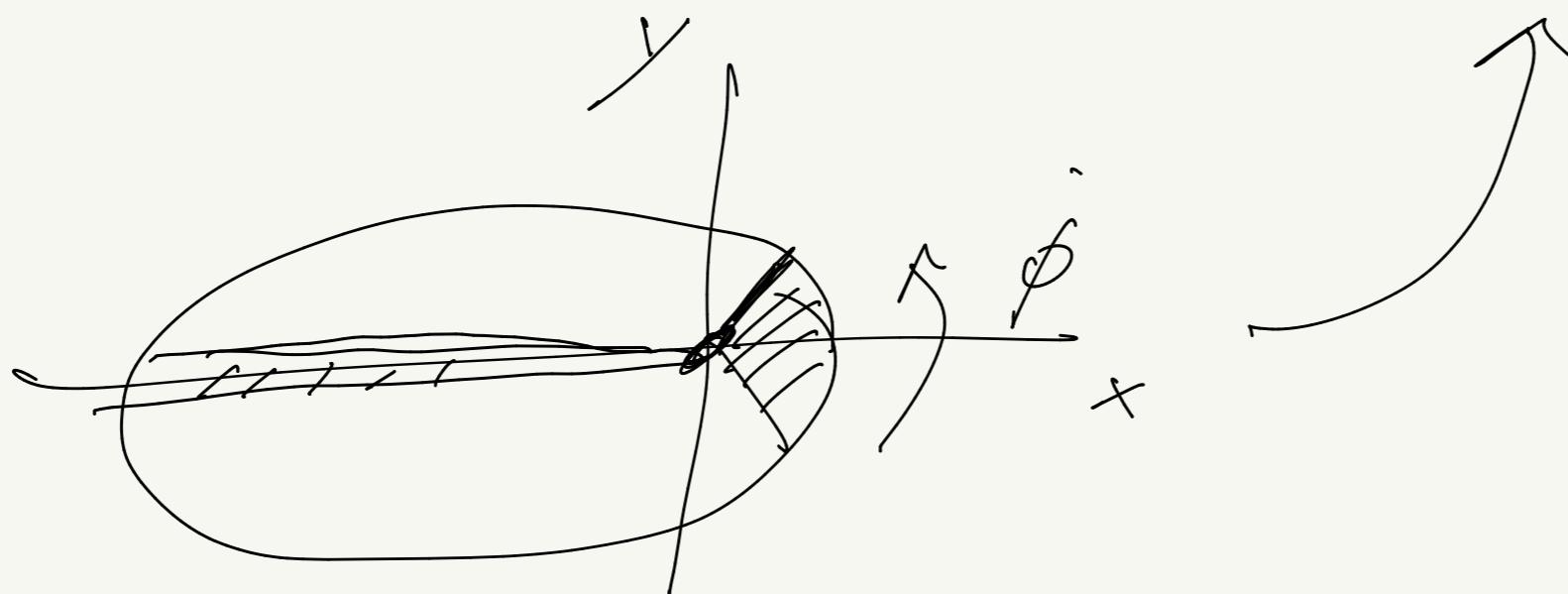
clock
 $a = b = r$

Angular velocity: $(r, \dot{\phi})$

$$\dot{\phi}$$

$$M_z = mr^2\dot{\phi}$$

$$\dot{\phi} = \frac{M_z}{mr^2}$$



Lecture #12

Thursday 9/30

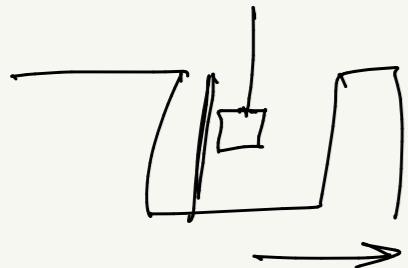
EXAM 1 : Tuer Oct 5th, MCom Z69

(★ If you are feeling sick, please contact me before the class to make arrangements for a remote exam.)

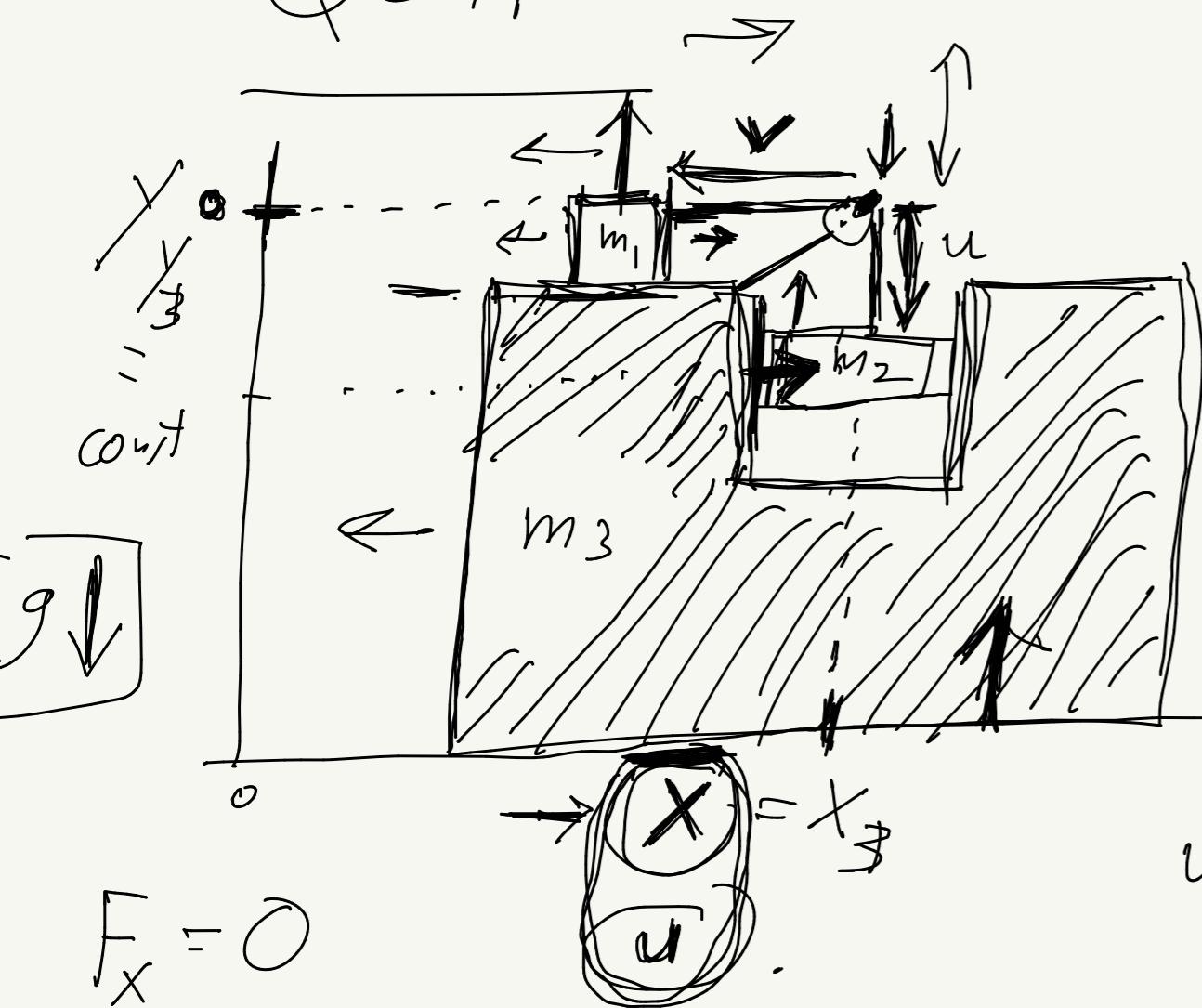
8 short answer questions - 8 pts

2 longer problems - 12 pts

$\frac{8 \text{ pts} + 12 \text{ pts}}{20 \text{ pts}}$ (total)



Q&A:



$$\ddot{y}_3 = 0, x_3 = X$$

$$x_2 = x_3$$

$$y_2 = y_3 - u$$

$$x_1 = x_3 - v$$

$$y_1 = y_3$$

$$u + v = l$$

$$v = l - u$$

$$T = \frac{1}{2} m_1 (\dot{x}_1^2 + \dot{y}_1^2)$$

$$+ \frac{1}{2} m_2 (\dot{x}_2^2 + \dot{y}_2^2)$$

$$+ \frac{1}{2} m_3 (\dot{x}_3^2 + \dot{y}_3^2)$$

$$U = m_1 g y_1 + m_2 g y_2 + m_3 g y_3$$

$$= m_1 g y_3 + m_2 g y_2 + m_3 g y_3$$

cont

$$= m_2 g (y_3 - u)$$

$$= m_1 g y_3 - m_2 g u = U$$

$$\begin{aligned}
 \rightarrow x_1 &= x_3 - v = x - (l-u) & \rightarrow \dot{x}_1 &= \dot{x} + \dot{u} \\
 x_2 &= x_3 = x & \rightarrow x_2 &= x \\
 x_3 &= x & \rightarrow \dot{x}_3 &= \dot{x} \\
 y_1 &= y_3 = \text{const} & \rightarrow \dot{y}_1 &= 0 \\
 y_2 &= y_3 - u & \rightarrow \dot{y}_2 &= -\dot{u} \\
 y_3 &= \text{const} & \rightarrow \dot{y}_3 &= 0
 \end{aligned}$$

↖

$$\begin{aligned}
 T &= \frac{1}{2} m_1 (\dot{x} + \dot{u})^2 + \frac{1}{2} m_2 (\dot{x} + \dot{u})^2 + \frac{1}{2} m_3 \dot{x}^2 \\
 &= \frac{1}{2} m_1 (\dot{x}^2 + \dot{u}^2 + 2\dot{x}\dot{u}) + \frac{1}{2} m_2 \dot{x}^2 + \frac{1}{2} m_3 \dot{x}^2 + \frac{1}{2} m_2 \dot{u}^2 \\
 &= \frac{1}{2} (m_1 + m_2 + m_3) \dot{x}^2 + \frac{1}{2} m_1 \dot{u}^2 + \boxed{m_1 \dot{x}\dot{u}} + \frac{1}{2} m_2 \dot{u}^2 \\
 &= \frac{1}{2} (m_1 + m_2 + m_3) \dot{x}^2 + \frac{1}{2} \cancel{(m_1 + m_2)} \dot{u}^2 + \cancel{m_1 \dot{x}\dot{u}}
 \end{aligned}$$

$U = -m_2 g \dot{u}$

$L = T - U$
 No x -dependence $\rightarrow O = P_x = \text{const}$
 $X_{\text{com}} = 0$

$E = T + U = \text{const}$
 $O = (m_1 + m_2 + m_3) \dot{x} + m_2 \dot{u}$

$$(m_1 + m_2 + m_3) \cancel{x}_{com} = m_1 x_1 + m_2 x_2 + m_3 x_3 = 0$$

$x_1 = x - l + u$

$$= (m_1 + m_2 + m_3)x - m_1 l + m_1 u \\ = 0$$

$$(m_1 + m_2 + m_3)x = m_1(l-u)$$

q_1 doesn't appear in Lagrangian

$$\frac{d}{dt} \left(\frac{\partial L}{\partial \dot{q}_1} \right) = \cancel{\frac{\partial L}{\partial q_1}} = 0 \quad p_1 = \frac{\partial L}{\partial \dot{q}_1} = \text{const}$$

$\cancel{\frac{\partial L}{\partial q_1}}$

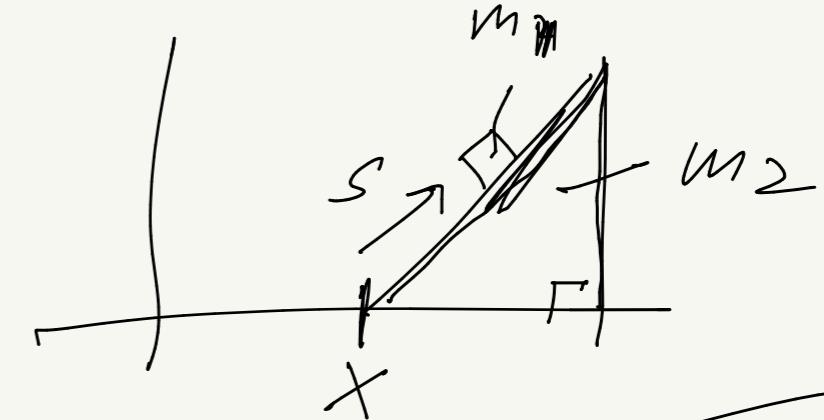
const

Constraints:

$$y_3 = \cos \varphi T = 0$$

$$x_1 = \cos \varphi T$$

$$x_2 = x_3 = x$$



$$x_1 = x_3 - (l - u) = x_3 - l + y_2 \rightarrow x_1 - x_3 + y_2 = -l$$

\rightarrow $y_2 = x_3 - u = -u$

\rightarrow $x_3 = x$

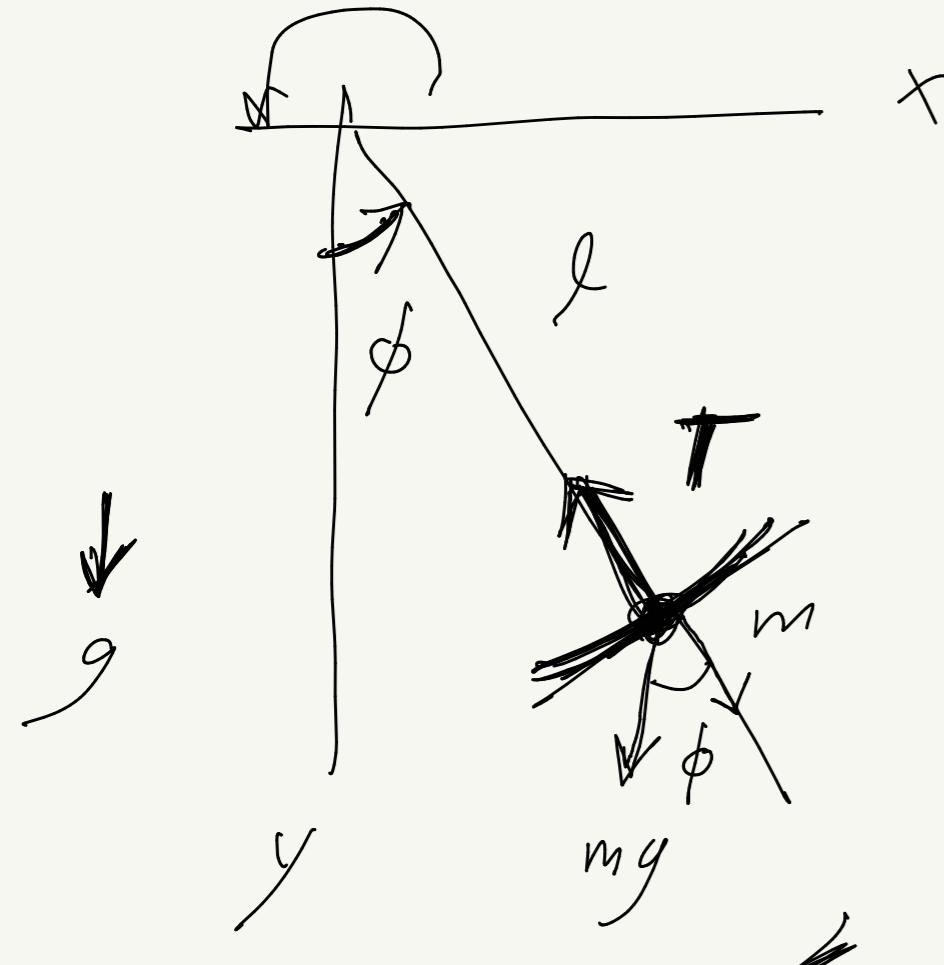
\rightarrow $y_2 = x - u$

\rightarrow $x_1 - x_3 + y_2 = -l$

6 DOF
 \rightarrow 4 constraints
 $\frac{2}{2}$ DOF

$y_3 = 0, \quad y_1 = \cos \varphi T, \quad x_2 - x_3 = 0$

$x_1 - x_3 + y_2 = -l$



$$\underline{F_{\text{radial}}}: \quad T - mg \cos \phi = m \ddot{\phi}_{\text{radial}}$$

$$\underline{F_{\text{tangential}}}: \quad mg \sin \phi = m \ddot{\phi}_{\text{tangential}}$$

$$l \ddot{\phi} = \ddot{\phi}_{\text{tangential}}$$

$$l \dot{\phi}^2 = \ddot{\phi}_{\text{radial}}$$

don't do work

$$L = T - U + \frac{1}{2} l \dot{\phi}^2$$

$$\varphi = T - l = 0,$$

$$T = \frac{1}{2} m (r^2 + r^2 \dot{\phi}^2)$$

$$U = -mgY$$

$$= -mg r \cos \phi$$

$$\frac{d}{dt} \left(\frac{\partial L}{\partial \dot{r}} \right) = \frac{\partial L}{\partial r}$$

$$\ddot{\phi}, \quad \dot{\phi} = r - l = 0$$

$$T = mg \cos \phi + m l \dot{\phi}^2$$

$$mg \sin \phi = -m l \ddot{\phi}$$

$$\ddot{\phi} = -\frac{g}{l} \sin \phi$$

$$F_c = m \vec{v} \times \vec{B}$$

$$F_c = -T r^2$$

furious

$$\vec{F}_c = - (m g r_0 \phi + m l \dot{\phi}^2) \hat{r}$$

$$= - \nabla U_{\text{const}}$$

$$W_{\text{path}} = \int_{\text{path}} \vec{F}_c \cdot d\vec{l}$$

$$= \int_{\text{path}} \vec{F} \cdot \vec{v} dt$$

$$\vec{F}_c \perp \vec{v}$$

$$\frac{d\vec{l}}{dt} dt$$

$$\vec{v} dt$$

