


CONSERVATIVE SYSTEMS $V = V(\{q_i\})$

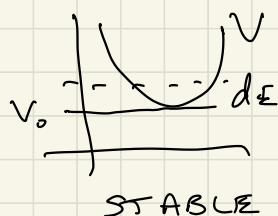
TIME INDEPENDENT

EQUIL $Q_i = - \frac{\partial V}{\partial q_i} \Big|_0 = 0$

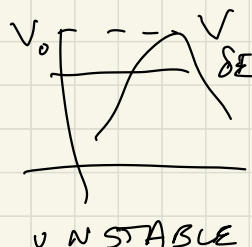
FORCES VANISH
V EXTREMUM

IF $\{\dot{q}_i\} = 0$ V_i THEN A SYSTEM WILL
STAY IN EQUIL

FOCUS ON STABLE
CASES



STABLE



UNSTABLE

$$q_i = q_{0i} + \eta_i \quad \eta_i = V_0$$

$$V(\{q_i\}) = V(\{q_{0i}\}) + \frac{\partial V}{\partial q_i} \Big|_0 \eta_i + \frac{1}{2} \frac{\partial^2 V}{\partial q_i \partial q_j} \Big|_0 \eta_i \eta_j$$

REPEATED INDICES $\Rightarrow$ IMPLIED SUMMATION

$$V(\{\eta_i\}) = \frac{1}{2} \frac{\partial^2 V}{\partial q_i \partial q_j} \Big|_0 \eta_i \eta_j = \frac{1}{2} V_{ij} \eta_i \eta_j$$

$V_{ij} = 0$ IF V INDEPENDENT OF q_i V_{ij} symmetric

$$T = \frac{1}{2} m_{ij} \dot{q}_i \dot{q}_j = \frac{1}{2} m_{ij} \dot{\eta}_i \dot{\eta}_j$$

T HOMOGENEOUS
QUADRATIC

IF $m_{ij}(\{q_i\})$ THEN WE CAN EXPAND IT

BUT T IS ALREADY 2ND ORDER IN $\dot{\eta}$

$$T = \frac{1}{2} T_{ij} \dot{\eta}_i \dot{\eta}_j$$

$$T_{ij} = m_{ij} \Big|_0$$

T_{ij} MUST BE SYMMETRIC

$$L = \frac{1}{2} (T_{ij} \dot{q}_i \dot{q}_j - V_{ij} q_i q_j) \quad \frac{d}{dt} \frac{\partial L}{\partial \dot{q}_i} - \frac{\partial L}{\partial q_i} = 0$$

EQ OF MOTION $T_{ij} \ddot{q}_j + V_{ij} q_j = 0$

MOST PROBLEMS DIAGONAL IN T IMPLIED $\sum_j$

$$L = \frac{1}{2} (T_i \dot{q}_i^2 - V_{ij} q_i q_j)$$

$$T_i \ddot{q}_i + \sum_j V_{ij} q_j = 0$$

NO SUM OVER i

$$\begin{aligned} T &= \frac{1}{2} \sum_{ij} T_{ij} \dot{q}_i \dot{q}_j \\ &= \frac{1}{2} (\dot{q}_1, \dots, \dot{q}_n) \begin{pmatrix} T_{ij} \end{pmatrix} \begin{pmatrix} \dot{q}_1 \\ \vdots \\ \dot{q}_n \end{pmatrix} \\ &= \frac{1}{2} (\dot{\vec{q}})^T \overleftrightarrow{T} \dot{\vec{q}} \end{aligned}$$

$$\begin{aligned} V &= \frac{1}{2} \sum_{ij} V_{ij} q_i q_j \\ &= \frac{1}{2} (q_1, \dots, q_n) \begin{pmatrix} V_{ij} \end{pmatrix} \begin{pmatrix} q_1 \\ \vdots \\ q_n \end{pmatrix} = \frac{1}{2} (\vec{q})^T \overleftrightarrow{V} \vec{q} \end{aligned}$$

EOM $T_{ij} \ddot{q}_j + V_{ij} q_j = 0$

$$\begin{pmatrix} T_{ij} \end{pmatrix} \begin{pmatrix} \ddot{q}_1 \\ \vdots \\ \ddot{q}_n \end{pmatrix} + \begin{pmatrix} V_{ij} \end{pmatrix} \begin{pmatrix} q_1 \\ \vdots \\ q_n \end{pmatrix} = 0$$

$$\overleftrightarrow{T} \ddot{\vec{q}} + \overleftrightarrow{V} \vec{q} = 0$$

OSCILLATORY ANSATZ $y_i = c a_i e^{-i\omega t}$

$$-\omega^2 \overleftrightarrow{T} \vec{a} + \overleftrightarrow{V} \vec{a} = \vec{0} \quad c a_i \in \mathbb{C}$$

$$(\overleftrightarrow{V} - \lambda \overleftrightarrow{T}) \vec{a} = \vec{0}$$

$$\lambda = \omega^2 \quad \vec{a} = \begin{pmatrix} a_1 \\ \vdots \\ a_n \end{pmatrix} \quad \vec{0} = \begin{pmatrix} 0 \\ \vdots \\ 0 \end{pmatrix}$$

LINEAR HOMOGENOUS

NONTRIVIAL SOLUTION IFF

$$\det(\overleftrightarrow{V} - \lambda \overleftrightarrow{T}) = 0$$

$$\begin{vmatrix} V_{11} - \lambda T_{11} & V_{12} - \lambda T_{12} & \dots \\ V_{21} - \lambda T_{21} & & \\ V_{31} - \lambda T_{31} & & \\ \vdots & & \end{vmatrix} = 0$$

FOR EACH λ_k THAT IS A SOLUTION

$\exists$ EIGENVECTOR $\vec{a}$ $\lambda_k \rightarrow \vec{a}_k \quad k=1, \dots, n$

USUAL $\overleftrightarrow{M} \vec{v} = \lambda \vec{v}$

$$\overleftrightarrow{V} \vec{a} = \lambda \overleftrightarrow{T} \vec{a}$$

SHOW THAT $\lambda_k \in \mathbb{R} \quad \lambda_k > 0$

$$\{\vec{a}_k\} = \{\vec{a}_1, \vec{a}_2, \dots, \vec{a}_n\}$$

ORTHOGONAL
REAL

$$\overleftrightarrow{V}, \overleftrightarrow{T} \in \mathbb{R}$$

$$\overleftrightarrow{V} \vec{a}_k = \lambda_k \overleftrightarrow{T} \vec{a}_k$$

$$\vec{a}_l^+ \overleftrightarrow{V} = \lambda_l^* \vec{a}_l^+ \overleftrightarrow{T}$$

$$\vec{a}_l^+ \overleftrightarrow{V} \vec{a}_k = \lambda_k \vec{a}_l^+ \overleftrightarrow{T} \vec{a}_k$$

$$\vec{a}_l^+ \overleftrightarrow{V} \vec{a}_k = \lambda_l^* \vec{a}_l^+ \overleftrightarrow{T} \vec{a}_k$$

$$0 = (\lambda_k - \lambda_l^*) \vec{a}_l^+ \overleftrightarrow{T} \vec{a}_k \quad k=l \Rightarrow (\lambda_k - \lambda_k^*) \vec{a}_k^+ \overleftrightarrow{T} \vec{a}_k = 0$$

$$\vec{a}_k = \vec{\alpha}_k + i\vec{\beta}_k \quad \vec{a}_k^\dagger = \vec{\alpha}_k^T - i\vec{\beta}_k^T$$

$$\underbrace{\vec{a}_k^\dagger \overleftrightarrow{\Pi} \vec{a}_k}_{\mathbb{R}} = \vec{\alpha}_k^T \overleftrightarrow{\Pi} \vec{\alpha}_k + \vec{\beta}_k^T \overleftrightarrow{\Pi} \vec{\beta}_k + i(\vec{\alpha}_k^T \overleftrightarrow{\Pi} \vec{\beta}_k - \vec{\beta}_k^T \overleftrightarrow{\Pi} \vec{\alpha}_k) \rightarrow 0$$

$\overleftrightarrow{\Pi}$ SYMMETRIC

$\alpha \overleftrightarrow{\Pi} \alpha$ and $\beta \overleftrightarrow{\Pi} \beta$ ARE KINETIC ENERGY-LIKE

$$\Rightarrow \lambda_k \in \mathbb{R} \quad \vec{a}_k \in \mathbb{R}$$

SOLVE $\overleftrightarrow{V} \vec{a}_k = \lambda_k \overleftrightarrow{\Pi} \vec{a}_k$ MULTIPLY BY $\vec{a}_k^T$

$$\lambda_k = \frac{\vec{a}_k^T \overleftrightarrow{V} \vec{a}_k}{\vec{a}_k^T \overleftrightarrow{\Pi} \vec{a}_k}$$

SCALAR SCALAR

$$\lambda_k \neq \frac{\overleftrightarrow{V} \vec{a}_k}{\overleftrightarrow{\Pi} \vec{a}_k}$$

VECTOR VECTOR

$\overleftrightarrow{V}$ IS MINIMUM @ EQUILIBRIUM

STABILITY $\Rightarrow \vec{a}_k^T \overleftrightarrow{V} \vec{a}_k \geq 0$

BOTTOM KE-like $\Rightarrow \vec{a}_k \overleftrightarrow{\Pi} \vec{a}_k > 0$

$$\lambda_k \geq 0 \quad \forall k \Rightarrow \omega_k = \sqrt{\lambda_k} \in \mathbb{R}$$

REAL

$$\Rightarrow \vec{a}_k \in \mathbb{R}$$

NORMAL MODES $C \vec{a}_k e^{i\sqrt{\lambda_k}t}$

$$(\vec{y}_i = C a_i e^{-i\omega t}) \Rightarrow \{\vec{y}_i\} = \{\vec{q}_{i0} + \vec{z}_i\}$$

$$= \{\vec{q}_{i0} + C(\vec{a}_k) e^{i\sqrt{\lambda_k}t}\}$$

GENERAL $\vec{y}(t) = \text{Re}\left(\sum_k C_k \vec{a}_k e^{i\sqrt{\lambda_k}t}\right)$

EXAMPLE 2

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

$$V = \frac{1}{2} k_1 x_1^2 + \frac{1}{2} k_2 (x_1 - x_2)^2 + \frac{1}{2} k_3 x_2^2$$

$$= \frac{1}{2} [(k_1 + k_2) x_1^2 + (k_2 + k_3) x_2^2 - 2k_2 x_1 x_2]$$

$$\overleftrightarrow{T} = \begin{pmatrix} m_1 & 0 \\ 0 & m_2 \end{pmatrix} \quad \overleftrightarrow{V} = \begin{pmatrix} k_1 + k_2 & -k_2 \\ -k_2 & k_2 + k_3 \end{pmatrix}$$

SIMPLIFY $M_1 = M_2$ $k_1 = k_3 = k$

$$|\overleftrightarrow{V} - \lambda \overleftrightarrow{T}| = \begin{vmatrix} k + k_2 - \lambda m & -k_2 \\ -k_2 & k + k_2 - \lambda m \end{vmatrix}$$

$$= ((k + k_2)^2 + \lambda^2 m^2 - 2(k + k_2) \lambda m) - k_2^2 = 0$$

$$= \lambda^2 - \frac{2(k + k_2)}{m} \lambda + \frac{k^2 + 2kk_2}{m^2} = 0$$

$$\lambda = \frac{2(k + k_2)}{m} \pm \frac{\left[\frac{4(k^2 + 2kk_2 + k_2^2)}{m^2} - \frac{4k^2 + 8kk_2}{m^2} \right]^{1/2}}{2}$$

$$\lambda = \frac{k + k_2}{m} \pm \frac{k_2}{m} \quad \lambda_1 = \frac{k + 2k_2}{m} \quad \lambda_2 = \frac{k}{m}$$

$$(\overleftrightarrow{V} - \lambda_1 \overleftrightarrow{T}) \vec{a}_1 = \begin{pmatrix} k + k_2 - (k + 2k_2) & -k_2 \\ -k_2 & k + k_2 - (k + 2k_2) \end{pmatrix} \begin{pmatrix} a_{11} \\ a_{21} \end{pmatrix}$$

$$= \begin{pmatrix} -k_2 & -k_2 \\ -k_2 & -k_2 \end{pmatrix} \begin{pmatrix} a_{11} \\ a_{12} \end{pmatrix} = 0 \quad \vec{a}_1 = \begin{pmatrix} 1 \\ -1 \end{pmatrix}$$

$$\lambda_2 = \frac{k}{m}$$

$$\left(\begin{array}{c} \leftarrow \\ \downarrow \\ \leftarrow \end{array} - \lambda_2 \begin{array}{c} \leftarrow \\ \downarrow \\ \leftarrow \end{array} \right) \vec{a}_2 = \begin{pmatrix} k+k_2-k & -k_2 \\ -k_2 & k+k_2-k \end{pmatrix} \begin{pmatrix} a_{21} \\ a_{22} \end{pmatrix}$$

$$= \begin{pmatrix} k_2 & -k_2 \\ -k_2 & k_2 \end{pmatrix} \begin{pmatrix} a_{21} \\ a_{22} \end{pmatrix} = 0 \Rightarrow \vec{a}_2 = \begin{pmatrix} 1 \\ 1 \end{pmatrix}$$

$$\omega_1 = \sqrt{\lambda_1} = \sqrt{\frac{k+2k_2}{m}} \quad \omega_2 = \sqrt{\lambda_2} = \sqrt{k/m}$$

PUT IN INITIAL CONDITIONS

$$x_1(0) = C \quad x_2(0) = 0 \quad \dot{x}_1(0) = \dot{x}_2(0) = 0$$

$$\vec{x}(t) = C_1 \underbrace{\begin{pmatrix} 1 \\ -1 \end{pmatrix}}_{\vec{a}_1} e^{i\omega_1 t} + C_2 \underbrace{\begin{pmatrix} 1 \\ 1 \end{pmatrix}}_{\vec{a}_2} e^{i\omega_2 t}$$

$$x_1: \operatorname{Re}(C_1 + C_2) = C$$

$$x_2: \operatorname{Re}(C_1 - C_2) = 0$$

$$\dot{x}_1: \operatorname{Im}(C_1 + C_2) = 0$$

$$\dot{x}_2: \operatorname{Im}(C_1 - C_2) = 0$$

$$C_1 = C_2 = \frac{C}{2}$$