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Notes. Michael Good. May 30,
2004. 1 Chapter 1: Elementary
Principles. 1.1 Mechanics of a
Single Particle. Classical
mechanics incorporates special
relativity. Classical refers to the
con-tradistinction to quantum

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Solution. Velocity: $v = dr/dt$.

Linear momentum: $p = mv$. Force: $F = dp/dt$.

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We have $F_3(p, Q) = - (eQ - 1)^2$

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$\tan p \text{ so } F_3 = 2eQ (eQ - 1) \tan p$
 $\frac{Q}{\sec^2 p} = - \frac{F_3}{q} = (eQ - 1)^2$
 The second of these may be solved to yield Q in terms of q and p : $P = -Q = \log (1 + q^{1/2} \cos p)$ and then we may plug this back into the equation for P to obtain $P = 2q^{1/2} \sin p + q \sin 2p$

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$$13 \quad | \quad 3 \quad | \quad (1 + i2) \quad i \quad (1 + i2) = 0$$

Let $q = 1 + i2$ Now $q \dot{q} = 0$ has
solution $q(t) = A e^{it}$ this is $1 + i2$
 $= A \cos t + iA \sin t$ and we see 1

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$(t) = A \cos t$ $2 (t) = A \sin t$ The x_3 axis is the symmetry axis of the body, so the angular velocity vector precesses about the body x_3 axis with a constant angular frequency $=$.

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$q; p = 1 \rightarrow [Q; P] q; p = [Q; P] Q; P.$

Hence Proved. 9.6 The

transformation equations between

two sets of coordinates are $Q =$

$\log(1 + p q \cos p) P = 2(1 + p$

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qcosp) p qsinp (a) Show directly from these transformation equations that Q, P are canonical variables if q and p are.

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Chapter 8 Problem 8.4 The

Lagrangian for a system can be

written as $L = \frac{1}{2} a \dot{x}^2 + b +$

$c \dot{x} \dot{y} + f y^2 x \dot{z} + g \dot{y} -$

$k x^2 + y^2$, where $a, b, c, f, g,$

and k are constants. What is the

Hamiltonian?

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solutions to the problems proposed
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1 Goldstein 8.1 1.1 Part (a) The Hamiltonian is given by $H(q_i; p_i; t) = p_i q_{\dot{i}} - L(q_i; q_{\dot{i}}; t)$ (1) where all the $q_{\dot{i}}$'s on the RHS are to be expressed in terms of q_i , p_i and t .

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Solution

Now, $dH = \frac{\partial H}{\partial q_i} dq_i + \frac{\partial H}{\partial p_i} dp_i + \frac{\partial H}{\partial t} dt$ (2) From (1), $dH = p_i dq_i + \frac{\partial L}{\partial q_i} dq_i + \frac{\partial L}{\partial p_i} dp_i + \frac{\partial L}{\partial t} dt = \frac{\partial L}{\partial q_i} dq_i + \frac{\partial L}{\partial p_i} dp_i + p_i \frac{\partial L}{\partial q_i} dq_i + \frac{\partial L}{\partial t} dt$ (3) Comparing (2) and (3) we get $\frac{\partial H}{\partial q}$

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Homework 3 - UMD

"Classical Mechanics" by Herbert Goldstein
"Mathematical Methods of Classical Mechanics" by

Vladimir Arnold Class Schedule:

Tu,Th 12:00-1:20 No classes on:

Tuesday, October 8 Thursday,

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Edition. Chapter 5, Question 1: If R_i
is an antisymmetric matrix
associated with the coordinates of
the i th mass point of a system,

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Solution
with elements $R_{mn} = \epsilon_{mnl} x_l$, show that the matrix of the inertia tensor can be written as: $I = -m_i(R_i)^2$.

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$$v^2 = r^2 \dot{\phi}^2 \quad (v^2 = \dot{r}^2 + r^2 \dot{\phi}^2 \cos^2 \theta)$$

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Solution $(1 + \cos \theta)^2 \cdot 2r^2 \dot{\theta}^2 + \dot{r}^2 + \frac{L^2}{2mr^2} + \frac{k}{r}$. Using r for a parabola from Goldstein's (3.55), and not forgetting that $k = L^2 / mr$, $L^2 = 2mk(1 + \cos \theta) m r$ we have $2k - 2r^2 L^2 / mkr = v_p^2 = m^2 r^4 L^2 / mr$. For the speed of the parabola, we then have $r = k / v_p =$

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Solution Thus $vp^2 = . vp = .$

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Classical Mechanics is a textbook
about that subject written by
Herbert Goldstein, a professor at
Columbia University. Intended for

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Solution momentum, kinetic energy of a rigid body. Inertia tensor, principal axes : Hwk #7, Ch 4: 4, 15, 21, 23, 24 (due Wed Nov 1, 11:30am)
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