

**PHY 711 Classical Mechanics and
Mathematical Methods
10-10:50 AM MWF Olin 103**

Plan for Lecture 23:

Rigid body rotational motion (Chap. 5)

- 1. Moment of inertia tensor**
- 2. Rotational equations of motion**

Course schedule

(Preliminary schedule -- subject to frequent adjustment.)

	Date	F&W Reading	Topic	Assignment
1	Wed, 8/29/2012	Chap. 1	Review of basic principles; Scattering theory	#1
2	Fri, 8/31/2012	Chap. 1	Scattering theory continued	#2
3	Mon, 9/03/2012	Chap. 1	Scattering theory continued	#3
4	Wed, 9/05/2012	Chap. 1 & 2	Scattering theory/Accelerated coordinate frame	#4
5	Fri, 9/07/2012	Chap. 2	Accelerated coordinate frame	#5
6	Mon, 9/10/2012	Chap. 3	Calculus of Variation	#6
7	Wed, 9/12/2012	Chap. 3	Calculus of Variation continued	
8	Fri, 9/14/2012	Chap. 3	Lagrangian	#7
9	Mon, 9/17/2012	Chap. 3 & 6	Lagrangian	#8
10	Wed, 9/19/2012	Chap. 3 & 6	Lagrangian	#9
11	Fri, 9/21/2012	Chap. 3 & 6	Lagrangian	#10
12	Mon, 9/24/2012	Chap. 3 & 6	Lagrangian and Hamiltonian	#11
13	Wed, 9/26/2012	Chap. 6	Lagrangian and Hamiltonian	#12
14	Fri, 9/28/2012	Chap. 6	Lagrangian and Hamiltonian	#13
15	Mon, 10/01/2012	Chap. 4	Small oscillations	#14
16	Wed, 10/03/2012	Chap. 4	Small oscillations	#15
17	Fri, 10/05/2012	Chap. 4	Small oscillations	
18	Mon, 10/08/2012	Chap. 7	Wave equation	Take Home Exam
19	Wed, 10/10/2012	Chap. 7	Wave equation	Take Home Exam
20	Fri, 10/12/2012	Chap. 7	Wave equation	Take Home Exam
21	Mon, 10/15/2012	Chap. 7	Wave equation	Exam due
22	Wed, 10/17/2012	Chap. 7, 5	Moment of inertia	
	Fri, 10/19/2012		Fall break	
23	Mon, 10/22/2012	Chap. 5	Rigid body rotation	#16
24	Wed, 10/24/2012	Chap. 5	Rigid body rotation	#17



$$T = \sum_p \frac{1}{2} m_p [(\boldsymbol{\omega} \cdot \boldsymbol{\omega})(\mathbf{r}_p \cdot \mathbf{r}_p) - (\mathbf{r}_p \cdot \boldsymbol{\omega})^2]$$

$$= \boldsymbol{\omega} \cdot \vec{\mathbf{I}} \cdot \boldsymbol{\omega}$$

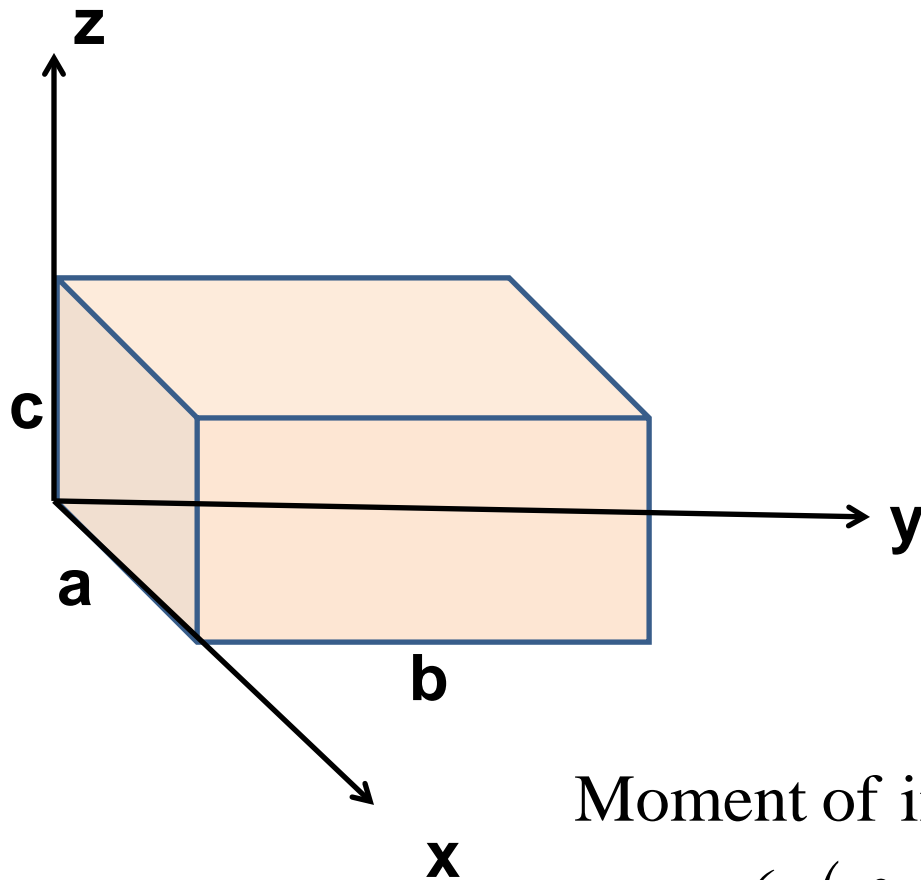
Moment of inertia tensor :

$$\vec{\mathbf{I}} \equiv \sum_p m_p (\mathbf{1} r_p^2 - \mathbf{r}_p \mathbf{r}_p) \quad (\text{dyad notation})$$

Matrix notation :

$$\vec{\mathbf{I}} \equiv \begin{pmatrix} I_{xx} & I_{xy} & I_{xz} \\ I_{yx} & I_{yy} & I_{yz} \\ I_{zx} & I_{zy} & I_{zz} \end{pmatrix}$$

$$I_{ij} \equiv \sum_p m_p (\delta_{ij} r_p^2 - r_{pi} r_{pj})$$



Matrix notation :

$$\vec{\mathbf{I}} \equiv \begin{pmatrix} I_{xx} & I_{xy} & I_{xz} \\ I_{yx} & I_{yy} & I_{yz} \\ I_{zx} & I_{zy} & I_{zz} \end{pmatrix}$$

$$I_{ij} \equiv \sum_p m_p \left(\delta_{ij} r_p^2 - r_{pi} r_{pj} \right)$$

Moment of inertia tensor :

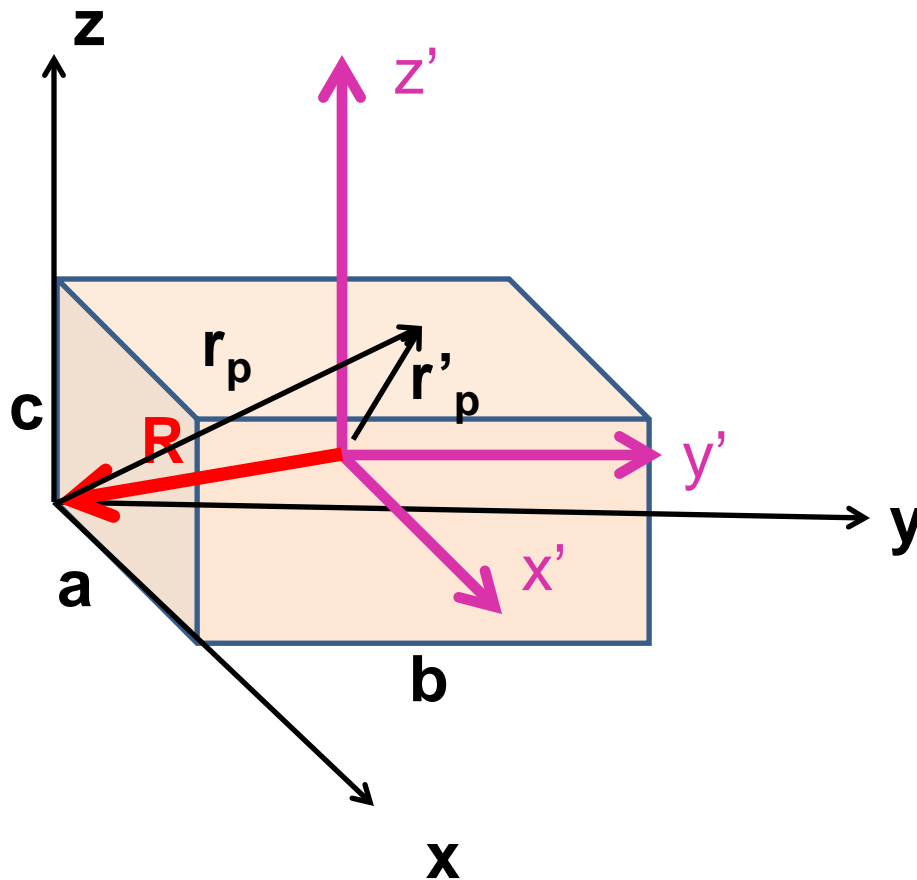
$$\vec{\mathbf{I}} = M \begin{pmatrix} \frac{1}{3}(b^2 + c^2) & -\frac{1}{4}ab & -\frac{1}{4}ac \\ -\frac{1}{4}ab & \frac{1}{3}(a^2 + c^2) & -\frac{1}{4}bc \\ -\frac{1}{4}ac & -\frac{1}{4}bc & \frac{1}{3}(a^2 + b^2) \end{pmatrix}$$

Properties of moment of inertia tensor:

- Symmetric matrix → real eigenvalues I_1, I_2, I_3
- → orthogonal eigenvectors

$$\vec{\mathbf{I}} \cdot \hat{\mathbf{e}}_i = I_i \hat{\mathbf{e}}_i \quad i = 1, 2, 3$$

Changing origin of rotation



$$I_{ij} \equiv \sum_p m_p (\delta_{ij} r_p^2 - r_{pi} r_{pj})$$

$$I'_{ij} \equiv \sum_p m_p (\delta_{ij} r'_p{}^2 - r'_{pi} r'_{pj})$$

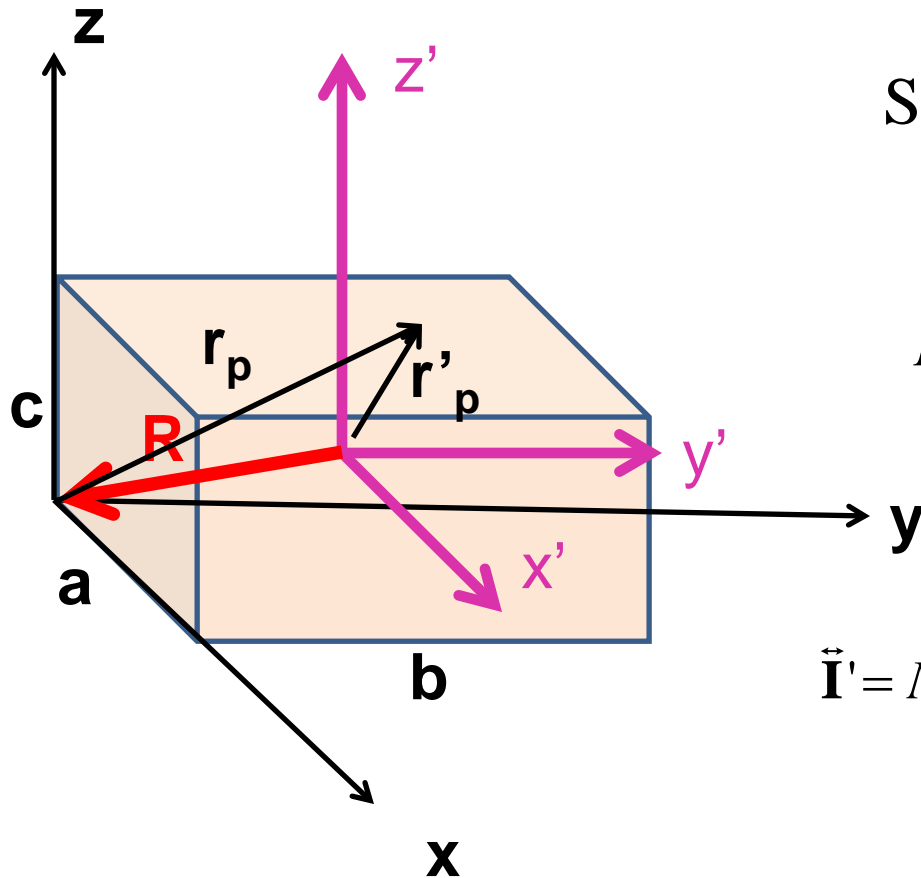
$$\mathbf{r}'_p = \mathbf{r}_p + \mathbf{R}$$

Define the center of mass :

$$\mathbf{r}_{CM} = \frac{\sum_p m_p \mathbf{r}_p}{\sum_p m_p} \equiv \frac{\sum_p m_p \mathbf{r}_p}{M}$$

$$I'_{ij} = I_{ij} + M(R^2 \delta_{ij} - R_i R_j) + M(2\mathbf{r}_{CM} \cdot \mathbf{R} \delta_{ij} - r_{CMi} R_j - R_i r_{CMj})$$

$$I'_{ij} = I_{ij} + M(R^2 \delta_{ij} - R_i R_j) + M(2\mathbf{r}_{CM} \cdot \mathbf{R} \delta_{ij} - r_{CMi} R_j - R_i r_{CMj})$$

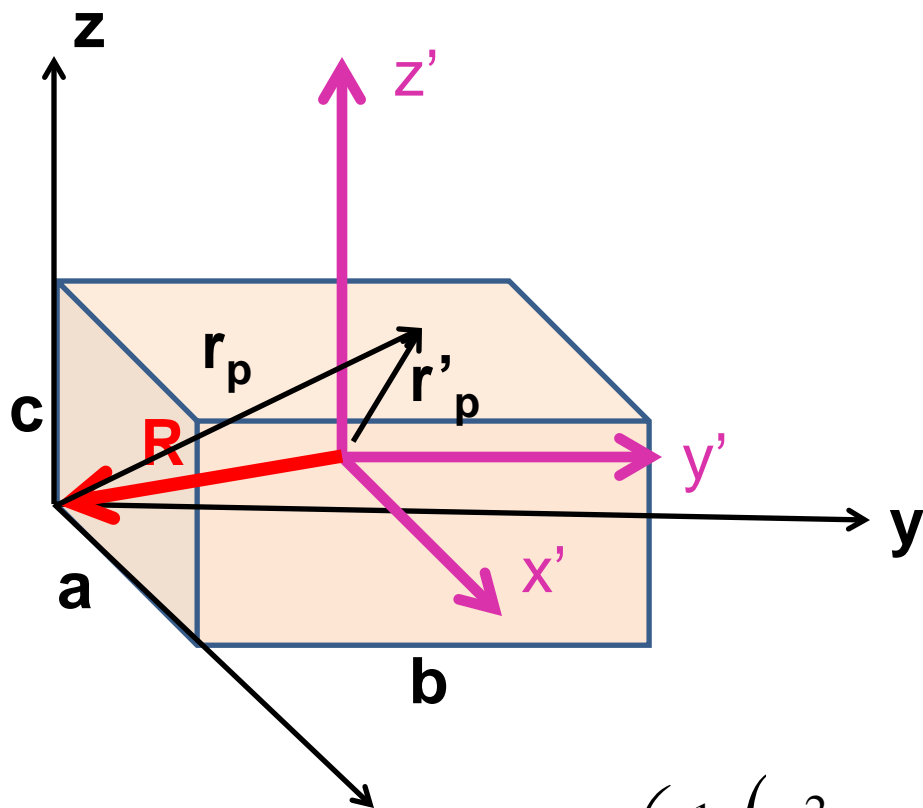


Suppose that $\mathbf{R} = -\frac{a}{2}\hat{\mathbf{x}} - \frac{b}{2}\hat{\mathbf{y}} - \frac{c}{2}\hat{\mathbf{z}}$

and $\mathbf{r}_{CM} = -\mathbf{R}$

$$I'_{ij} = I_{ij} - M(R^2 \delta_{ij} - R_i R_j)$$

$$\begin{aligned} \tilde{\mathbf{I}}' = M & \begin{pmatrix} \frac{1}{3}(b^2 + c^2) & -\frac{1}{4}ab & -\frac{1}{4}ac \\ -\frac{1}{4}ab & \frac{1}{3}(a^2 + c^2) & -\frac{1}{4}bc \\ -\frac{1}{4}ac & -\frac{1}{4}bc & \frac{1}{3}(a^2 + b^2) \end{pmatrix} \\ & - M \begin{pmatrix} \frac{1}{4}(b^2 + c^2) & -\frac{1}{4}ab & -\frac{1}{4}ac \\ -\frac{1}{4}ab & \frac{1}{4}(a^2 + c^2) & -\frac{1}{4}bc \\ -\frac{1}{4}ac & -\frac{1}{4}bc & \frac{1}{4}(a^2 + b^2) \end{pmatrix} \end{aligned}$$



$$\mathbf{x} \vec{\mathbf{I}}' = M \begin{pmatrix} \frac{1}{12}(b^2 + c^2) & 0 & 0 \\ 0 & \frac{1}{12}(a^2 + c^2) & 0 \\ 0 & 0 & \frac{1}{12}(a^2 + b^2) \end{pmatrix}$$

Descriptions of rotation about a given origin

For general coordinate system

$$T = \frac{1}{2} \sum_{ij} I_{ij} \omega_i \omega_j$$

For (body fixed) coordinate system that diagonalizes moment of inertia tensor :

$$\vec{\mathbf{I}} \cdot \hat{\mathbf{e}}_i = I_i \hat{\mathbf{e}}_i \quad i = 1, 2, 3$$

$$\boldsymbol{\omega} = \tilde{\omega}_1 \hat{\mathbf{e}}_1 + \tilde{\omega}_2 \hat{\mathbf{e}}_2 + \tilde{\omega}_3 \hat{\mathbf{e}}_3$$

$$\Rightarrow T = \frac{1}{2} \sum_i I_i \tilde{\omega}_i^2$$

Descriptions of rotation about a given origin -- continued

Time rate of change of angular momentum

$$\frac{d\mathbf{L}}{dt} = \left(\frac{d\mathbf{L}}{dt} \right)_{body} + \boldsymbol{\omega} \times \mathbf{L}$$

For (body fixed) coordinate system that diagonalizes moment of inertia tensor :

$$\vec{\mathbf{I}} \cdot \hat{\mathbf{e}}_i = I_i \hat{\mathbf{e}}_i \quad \boldsymbol{\omega} = \tilde{\omega}_1 \hat{\mathbf{e}}_1 + \tilde{\omega}_2 \hat{\mathbf{e}}_2 + \tilde{\omega}_3 \hat{\mathbf{e}}_3$$

$$\mathbf{L} = I_1 \tilde{\omega}_1 \hat{\mathbf{e}}_1 + I_2 \tilde{\omega}_2 \hat{\mathbf{e}}_2 + I_3 \tilde{\omega}_3 \hat{\mathbf{e}}_3$$

$$\begin{aligned} \frac{d\mathbf{L}}{dt} = & I_1 \dot{\tilde{\omega}}_1 \hat{\mathbf{e}}_1 + I_2 \dot{\tilde{\omega}}_2 \hat{\mathbf{e}}_2 + I_3 \dot{\tilde{\omega}}_3 \hat{\mathbf{e}}_3 + \tilde{\omega}_2 \tilde{\omega}_3 (I_3 - I_2) \hat{\mathbf{e}}_1 \\ & + \tilde{\omega}_3 \tilde{\omega}_1 (I_1 - I_3) \hat{\mathbf{e}}_2 + \tilde{\omega}_1 \tilde{\omega}_2 (I_2 - I_1) \hat{\mathbf{e}}_3 \end{aligned}$$

Descriptions of rotation about a given origin -- continued

Note that the torque equation

$$\frac{d\mathbf{L}}{dt} = \left(\frac{d\mathbf{L}}{dt} \right)_{body} + \boldsymbol{\omega} \times \mathbf{L} = \boldsymbol{\tau}$$

is very difficult to solve directly in the body fixed frame.

For $\boldsymbol{\tau} = 0$ we can solve the Euler equations :

$$\begin{aligned} \frac{d\mathbf{L}}{dt} = & I_1 \dot{\tilde{\omega}}_1 \hat{\mathbf{e}}_1 + I_2 \dot{\tilde{\omega}}_2 \hat{\mathbf{e}}_2 + I_3 \dot{\tilde{\omega}}_3 \hat{\mathbf{e}}_3 + \tilde{\omega}_2 \tilde{\omega}_3 (I_3 - I_2) \hat{\mathbf{e}}_1 \\ & + \tilde{\omega}_3 \tilde{\omega}_1 (I_1 - I_3) \hat{\mathbf{e}}_2 + \tilde{\omega}_1 \tilde{\omega}_2 (I_2 - I_1) \hat{\mathbf{e}}_3 = 0 \end{aligned}$$

Euler equations for rotation in body fixed frame :

$$I_1 \dot{\tilde{\omega}}_1 + \tilde{\omega}_2 \tilde{\omega}_3 (I_3 - I_2) = 0$$

$$I_2 \dot{\tilde{\omega}}_2 + \tilde{\omega}_3 \tilde{\omega}_1 (I_1 - I_3) = 0$$

$$I_3 \dot{\tilde{\omega}}_3 + \tilde{\omega}_1 \tilde{\omega}_2 (I_2 - I_1) = 0$$

Solution for symmetric top -- $I_2 = I_1$:

$$I_1 \dot{\tilde{\omega}}_1 + \tilde{\omega}_2 \tilde{\omega}_3 (I_3 - I_1) = 0$$

$$I_1 \dot{\tilde{\omega}}_2 + \tilde{\omega}_3 \tilde{\omega}_1 (I_1 - I_3) = 0$$

$$I_3 \dot{\tilde{\omega}}_3 = 0 \quad \Rightarrow \quad \tilde{\omega}_3 = (\text{constant})$$

Define : $\Omega \equiv \tilde{\omega}_3 \frac{I_3 - I_1}{I_1}$

$$\dot{\tilde{\omega}}_1 = -\tilde{\omega}_2 \Omega$$

$$\dot{\tilde{\omega}}_2 = \tilde{\omega}_1 \Omega$$

Solution of Euler equations for a symmetric top -- continued

$$\dot{\tilde{\omega}}_1 = -\tilde{\omega}_2 \Omega \qquad \dot{\tilde{\omega}}_2 = \tilde{\omega}_1 \Omega$$

$$\text{where } \Omega \equiv \tilde{\omega}_3 \frac{I_3 - I_1}{I_1}$$

$$\begin{aligned} \text{Solution : } \quad \tilde{\omega}_1(t) &= A \cos(\Omega t + \varphi) \\ \tilde{\omega}_2(t) &= A \sin(\Omega t + \varphi) \end{aligned}$$

$$T = \frac{1}{2} \sum_i I_i \tilde{\omega}_i^2 = \frac{1}{2} I_1 A^2 + \frac{1}{2} I_3 \tilde{\omega}_3^2$$

Euler equations for rotation in body fixed frame :

$$I_1 \dot{\tilde{\omega}}_1 + \tilde{\omega}_2 \tilde{\omega}_3 (I_3 - I_2) = 0$$

$$I_2 \dot{\tilde{\omega}}_2 + \tilde{\omega}_3 \tilde{\omega}_1 (I_1 - I_3) = 0$$

$$I_3 \dot{\tilde{\omega}}_3 + \tilde{\omega}_1 \tilde{\omega}_2 (I_2 - I_1) = 0$$

Solution for asymmetric top -- $I_3 \neq I_2 \neq I_1$:

$$I_1 \dot{\tilde{\omega}}_1 + \tilde{\omega}_2 \tilde{\omega}_3 (I_3 - I_2) = 0$$

$$I_2 \dot{\tilde{\omega}}_2 + \tilde{\omega}_3 \tilde{\omega}_1 (I_1 - I_3) = 0$$

$$I_3 \dot{\tilde{\omega}}_3 + \tilde{\omega}_1 \tilde{\omega}_2 (I_2 - I_1) = 0$$

Suppose : $\dot{\tilde{\omega}}_3 \approx 0$

Define : $\Omega_1 \equiv \tilde{\omega}_3 \frac{I_3 - I_2}{I_1}$

Define : $\Omega_2 \equiv \tilde{\omega}_3 \frac{I_3 - I_1}{I_2}$