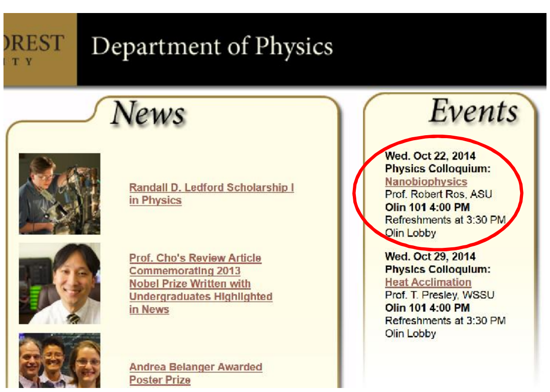
PHY 711 Classical Mechanics and Mathematical Methods
10-10:50 AM MWF Olin 103

Plan for Lecture 24:

Rotational motion (Chapter 5)

1. **Rigid body motion**
2. **Moment of inertia tensor**

7	Wed, 9/10/2014	Chap. 3	Hamilton's principle	#7
8	Fri, 9/12/2014	Chap. 3 & 6	Hamilton's principle	#8
9	Mon, 9/15/2014	Chap. 3 & 6	Lagrangians with constraints	#9
10	Wed, 9/17/2014	Chap. 3 & 6	Lagrangians and constants of motion	#10
11	Fri, 9/19/2014	Chap. 3 & 6	Hamiltonian formalism	#11
12	Mon, 9/22/2014	Chap. 3 & 6	Hamiltonian formalism	#11
13	Wed, 9/24/2014	Chap. 3 & 6	Hamiltonian Jacobi transformations	
14	Fri, 9/26/2014	Chap. 4	Small oscillations	Begin Take-Home
15	Mon, 9/29/2014	Chap. 4	Normal modes of motion	Continue Take-Home
16	Wed, 10/01/2014	Chap. 4	Normal modes of motion	Continue Take-Home
17	Fri, 10/03/2014	Chap. 4	Normal modes of motion	Take-Home due
18	Mon, 10/06/2014	Chap. 7	Wave motion	#12
19	Wed, 10/08/2014	Chap. 7	Sturm-Liouville Equations	#13
20	Fri, 10/10/2014	Chap. 7	Sturm-Liouville Equations	#13
21	Mon, 10/13/2014	Chap. 7	Sturm-Liouville Equations	#14
22	Wed, 10/15/2014	Appendix A	Contour integration methods	#15
	Fri, 10/17/2014		Fall break -- no class	
23	Mon, 10/20/2014	Appendix A	Fourier transforms	#16
24	Wed, 10/22/2014	Chap. 5	Motion of Rigid Bodies	#17
25	Fri, 10/24/2014	Chap. 5	Motion of Rigid Bodies	#18
26	Mon, 10/27/2014			



WFU Physics Colloquium

TITLE: Nanobiophysics: From Single Molecules to Living Cells

SPEAKER: Professor Robert Ros,

Department of Physics,
Arizona State University

TIME: Wednesday October 22, 2014 at 4:00 PM

PLACE: Room 101 Olin Physical Laboratory

Refreshments will be served at 3:30 PM in the Olin Lounge. All interested persons are cordially invited to attend.

ABSTRACT

Forces and mechanical properties play a central role in many biological processes covering a huge range of length and time scale: from the movement of whole organisms over the adhesion, migration, proliferation of cells, down to the mechanics and interactions of single molecules. For example cells are able to sense external forces (mechanosensing), translate these mechanical forces into biochemical signals (mechanotransduction) and react to these signals (mechanoresponse). Mechanics also plays an important role on the level of single biomolecules. For example, forces act between ligands and receptors, forces induce conformational changes in biomolecules, and the mechanical properties of biomolecules are often related to their function.

The physics of rigid body motion; body fixed frame vs inertial frame:

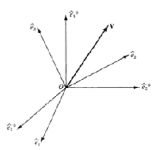


Figure 6.1 Transformation to a rotating coordinate system.

Let **V** be a general vector, e.g., the position of a particle. This vector can be characterized by its components with respect to either orthonormal triad. Thus we can write

$$\mathbf{V} = \sum_{i=1}^{3} V_i^0 \hat{e}_i^0 \qquad (6.1a)$$

$$\mathbf{V} = \sum_{i=1}^{3} V_i \hat{e}_i \qquad (6.1b)$$

Comparison of analysis in “inertial frame” versus “non-inertial frame”

Denote by $\hat{e}_i^0$ a fixed coordinate system

Denote by $\hat{e}_i$ a moving coordinate system

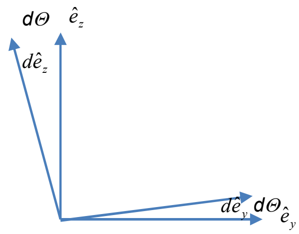
$$\mathbf{V} = \sum_{i=1}^{3} V_i^0 \hat{e}_i^0 = \sum_{i=1}^{3} V_i \hat{e}_i$$

$$\left(\frac{d\mathbf{V}}{dt}\right)_{inertial} = \sum_{i=1}^{3} \frac{dV_i^0}{dt}\hat{e}_i^0 = \sum_{i=1}^{3} \frac{dV_i}{dt}\hat{e}_i + \sum_{i=1}^{3} V_i \frac{d\hat{e}_i}{dt}$$

$$\text{Define : } \left(\frac{d\mathbf{V}}{dt}\right)_{body} \equiv \sum_{i=1}^{3} \frac{dV_i}{dt}\hat{e}_i$$

$$\Rightarrow \left(\frac{d\mathbf{V}}{dt}\right)_{inertial} = \left(\frac{d\mathbf{V}}{dt}\right)_{body} + \sum_{i=1}^{3} V_i \frac{d\hat{e}_i}{dt}$$

Properties of the frame motion (rotation):



$$d\hat{e}_y = d\Theta \hat{e}_z$$
$$d\hat{e}_z = -d\Theta \hat{e}_y$$
$$\Rightarrow d\hat{\mathbf{e}} = d\mathbf{\Theta} \times \hat{\mathbf{e}}$$
$$\frac{d\hat{\mathbf{e}}}{dt} = \frac{d\mathbf{\Theta}}{dt} \times \hat{\mathbf{e}}$$
$$\frac{d\hat{\mathbf{e}}}{dt} = \boldsymbol{\omega} \times \hat{\mathbf{e}}$$

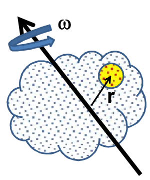
$$\begin{pmatrix} d\hat{e}_y \\ d\hat{e}_z \end{pmatrix} = \begin{pmatrix} \cos(d\Theta) & \sin(d\Theta) \\ -\sin(d\Theta) & \cos(d\Theta) \end{pmatrix} \begin{pmatrix} \hat{e}_y \\ \hat{e}_z \end{pmatrix} - \begin{pmatrix} \hat{e}_y \\ \hat{e}_z \end{pmatrix}$$

$$\left(\frac{d\mathbf{V}}{dt}\right)_{inertial} = \left(\frac{d\mathbf{V}}{dt}\right)_{body} + \sum_{i=1}^{3} V_i \frac{d\hat{e}_i}{dt}$$
$$\left(\frac{d\mathbf{V}}{dt}\right)_{inertial} = \left(\frac{d\mathbf{V}}{dt}\right)_{body} + \boldsymbol{\omega} \times \mathbf{V}$$

Effects on acceleration:

$$\left(\frac{d}{dt}\frac{d\mathbf{V}}{dt}\right)_{inertial} = \left(\left(\frac{d}{dt}\right)_{body} + \boldsymbol{\omega} \times\right)\left\{\left(\frac{d\mathbf{V}}{dt}\right)_{body} + \boldsymbol{\omega} \times \mathbf{V}\right\}$$
$$\left(\frac{d^2\mathbf{V}}{dt^2}\right)_{inertial} = \left(\frac{d^2\mathbf{V}}{dt^2}\right)_{body} + 2\boldsymbol{\omega} \times \left(\frac{d\mathbf{V}}{dt}\right)_{body} + \frac{d\boldsymbol{\omega}}{dt} \times \mathbf{V} + \boldsymbol{\omega} \times \boldsymbol{\omega} \times \mathbf{V}$$

Kinetic energy of rigid body :



$$\left(\frac{d\mathbf{r}}{dt}\right)_{inertial} = \left(\frac{d\mathbf{r}}{dt}\right)_{body} + \boldsymbol{\omega} \times \mathbf{r}$$
$$\left(\frac{d\mathbf{r}}{dt}\right)_{inertial} = \boldsymbol{\omega} \times \mathbf{r}$$
$$T = \sum_p \frac{1}{2} m_p v_p^2 = \sum_p \frac{1}{2} m_p \left(|\boldsymbol{\omega} \times \mathbf{r}_p|\right)^2$$
$$= \sum_p \frac{1}{2} m_p (\boldsymbol{\omega} \times \mathbf{r}_p) \cdot (\boldsymbol{\omega} \times \mathbf{r}_p)$$
$$= \sum_p \frac{1}{2} m_p \left[(\boldsymbol{\omega} \cdot \boldsymbol{\omega})(\mathbf{r}_p \cdot \mathbf{r}_p) - (\mathbf{r}_p \cdot \boldsymbol{\omega})^2\right]$$

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

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

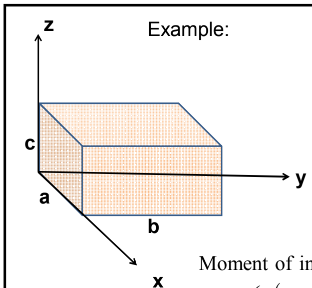
Moment of inertia tensor :

$$\ddot{\mathbf{I}} \equiv \sum_p m_p \left(\mathbf{1} r_p^2 - \mathbf{r}_p \mathbf{r}_p \right) \qquad \text{(dyad notation)}$$

Matrix notation :

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

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



Example:

Moment of inertia tensor :

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

Properties of moment of inertia tensor:

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

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

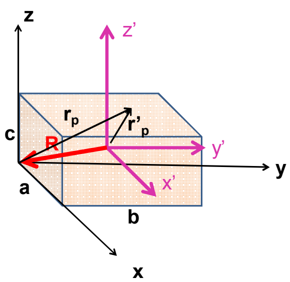
Moment of inertia tensor :

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

For $a = b = c$:

$$I_1 = \frac{1}{6} M a^2 \quad I_2 = \frac{11}{12} M a^2 \quad I_3 = \frac{11}{12} M a^2$$

Changing origin of rotation



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

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

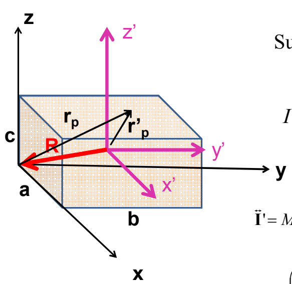
$$\mathbf{r}'_p = \mathbf{r}_p + \mathbf{R}$$

Define the center of mass :

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

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

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

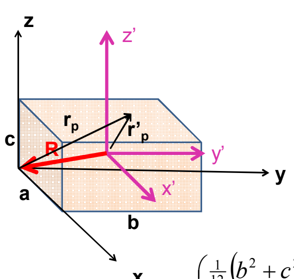


Suppose that $\mathbf{R} = -\frac{a}{2}\hat{\mathbf{x}} - \frac{b}{2}\hat{\mathbf{y}} - \frac{c}{2}\hat{\mathbf{z}}$

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

$$I'_{ij} = I_{ij} - M\left(R^2\delta_{ij} - R_iR_j\right)$$

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



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

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 :

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

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

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

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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 :

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

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

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

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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 :

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

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

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

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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 :

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

Euler equations for rotation in body fixed frame :

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

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

$$I_1\dot{\tilde{\omega}}_1 + \tilde{\omega}_2\tilde{\omega}_3\left(I_3 - I_1\right) = 0$$
$$I_1\dot{\tilde{\omega}}_2 + \tilde{\omega}_3\tilde{\omega}_1\left(I_1 - I_3\right) = 0$$
$$I_3\dot{\tilde{\omega}}_3 = 0 \qquad \Rightarrow \tilde{\omega}_3 = \text{(constant)}$$

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

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

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

Solution : $\tilde{\omega}_1(t) = A\cos(\Omega t + \varphi)$

$\tilde{\omega}_2(t) = A\sin(\Omega t + \varphi)$

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

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

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