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

Discussion of Lecture 10 – Chap. 3&6 in F&W

Lagrangian mechanics

1. Lagrange's equations in the presence of velocity dependent potentials – such as electromagnetic interactions.
2. Effects of constraints

PHY 711 Classical Mechanics and Mathematical Methods

MWF 10 AM-10:50 AM	OPL 103	http://www.wfu.edu/~natalie/f21phy711/

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Course schedule

(Preliminary schedule -- subject to frequent adjustment.)

	Date	F&W Reading	Topic	Assignment	Due
1	Mon, 8/23/2021	Chap. 1	Introduction	#1	8/27/2021
2	Wed, 8/25/2021	Chap. 1	Scattering theory	#2	8/30/2021
3	Fri, 8/27/2021	Chap. 1	Scattering theory		
4	Mon, 8/30/2021	Chap. 1	Scattering theory	#3	9/01/2021
5	Wed, 9/01/2021	Chap. 1	Summary of scattering theory	#4	9/03/2021
6	Fri, 9/03/2021	Chap. 2	Non-inertial coordinate systems	#5	9/06/2021
7	Mon, 9/06/2021	Chap. 3	Calculus of Variation	#6	9/10/2021
8	Wed, 9/08/2021	Chap. 3	Calculus of Variation		
9	Fri, 9/10/2021	Chap. 3 & 6	Lagrangian Mechanics	#7	9/13/2021
10	Mon, 9/13/2021	Chap. 3 & 6	Lagrangian Mechanics	#8	9/17/2021

PHY 711 – Assignment #8

September 13, 2021

The material for this exercise is covered in the lecture notes and in Chapters 3 and 6 of Fetter and Walecka.

1. A particle of mass m and charge q is subjected to a vector potential $\mathbf{A}(\mathbf{r},t) = -(E_0ct + B_0x)\hat{\mathbf{z}}$. (Note that we are using the cgs Gaussian units of your text book.) Here E_0 denotes a constant electric field amplitude and B_0 denotes a constant magnetic field amplitude. The initial particle position is $\mathbf{r}(0) = 0$ and the initial particle velocity is $\dot{\mathbf{r}}(0) = 0$.

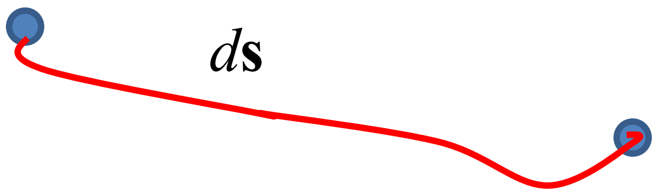
   (a) Determine the Lagrangian $L(x, y, z, \dot{x}, \dot{y}, \dot{z}, t)$ which describes the particle's motion.

   (b) Write the Euler-Lagrange equations for this system.

   (c) Find and evaluate the constants of motion for this system.

   (d) Find the particle trajectories $x(t)$, $y(t)$, $z(t)$ by solving the equations and imposing the given initial conditions.

Previously derived form for the Lagrangian --



Generalized coordinates :

$q_\sigma(\{x_i\})$

$$(\mathbf{F} - m\mathbf{a}) \cdot d\mathbf{s} = -\sum_\sigma \frac{\partial U}{\partial q_\sigma}\delta q_\sigma - \sum_\sigma \left(\frac{d}{dt}\frac{\partial T}{\partial \dot{q}_\sigma} - \frac{\partial T}{\partial q_\sigma} \right)\delta q_\sigma = 0$$

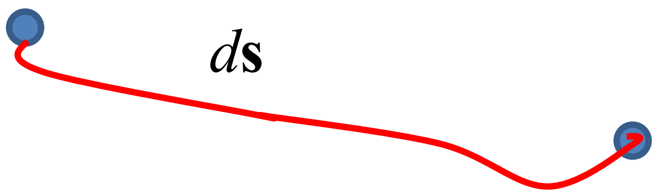
$$= \quad -\sum_\sigma \left(\frac{d}{dt}\frac{\partial (T-U)}{\partial \dot{q}_\sigma} - \frac{\partial (T-U)}{\partial q_\sigma} \right)\delta q_\sigma = 0$$

$$= \quad -\sum_\sigma \left(\frac{d}{dt}\frac{\partial L}{\partial \dot{q}_\sigma} - \frac{\partial L}{\partial q_\sigma} \right)\delta q_\sigma = 0$$

$$L(q_\sigma, \dot{q}_\sigma; t) = T - U$$

Note : This is only true if

$$\frac{\partial U}{\partial \dot{q}_\sigma} = 0$$



Generalized coordinates :

$$q_\sigma(\{x_i\})$$

Define - - Lagrangian : $\quad L \equiv T - U$

$$L = L(\{q_\sigma\}, \{\dot{q}_\sigma\}, t)$$

$$(\mathbf{F}\text{-}m\mathbf{a}) \cdot d\mathbf{s} = -\sum_\sigma \left(\frac{d}{dt} \frac{\partial L}{\partial \dot{q}_\sigma} - \frac{\partial L}{\partial q_\sigma} \right) \delta q_\sigma = 0$$

$$\Rightarrow \text{Minimization integral}: \quad S = \int_{t_i}^{t_f} L(\{q_\sigma\}, \{\dot{q}_\sigma\}, t)\, dt$$

➔Hamilton's principle from the "backwards" application of the Euler-Lagrange equations to

Define -- Lagrangian: $\quad L \equiv T - U$

$$L = L\left(\{q_\sigma\}, \{\dot{q}_\sigma\}, t\right)$$

Summary –

Hamilton's principle:

Given the Lagrangian function: $L = L\left(\{q_\sigma\},\{\dot{q}_\sigma\},t\right) \equiv T - U,$

The physical trajectories of the generalized coordinates $\{q_\sigma(t)\}$

are those which minimize the action: $S = \int L\left(\{q_\sigma\},\{\dot{q}_\sigma\},t\right)dt$

Euler-Lagrange equations:

$$\sum_\sigma \left(\frac{d}{dt}\frac{\partial L}{\partial \dot{q}_\sigma} - \frac{\partial L}{\partial q_\sigma} \right)\delta q_\sigma = 0 \quad \Rightarrow \text{for each } \sigma: \quad \left(\frac{d}{dt}\frac{\partial L}{\partial \dot{q}_\sigma} - \frac{\partial L}{\partial q_\sigma} \right) = 0$$

Note: in "proof" of Hamilton's principle:

$$\left(\frac{d}{dt}\frac{\partial L}{\partial \dot{q}_\sigma} - \frac{\partial L}{\partial q_\sigma}\right) = 0 \quad \text{for} \quad L = L(\{q_\sigma\}, \{\dot{q}_\sigma\}, t) \equiv T - U$$

It was necessary to assume that :

$$\frac{d}{dt}\frac{\partial U}{\partial \dot{q}_\sigma} \quad \text{does not contribute to the result.}$$

$\Rightarrow$ How can we represent velocity-dependent forces?

Why do we need velocity dependent forces?

a. Friction is sometimes represented as a velocity dependent force. (difficult to treat with Lagrangian mechanics.)
b. Lorentz force on a moving charged particle in the presence of a magnetic field.

Lorentz forces:

For particle of charge q in an electric field $\mathbf{E}(\mathbf{r},t)$ and magnetic field $\mathbf{B}(\mathbf{r},t)$:

Lorentz force: $\mathbf{F} = q\left(\mathbf{E} + \frac{1}{c}\mathbf{v}\times\mathbf{B}\right)$

x – component: $F_x = q\left(E_x + \frac{1}{c}\left(\mathbf{v}\times\mathbf{B}\right)_x\right)$

In this case, it is convenient to use cartesian coordinates

$$L = L\left(x, y, z, \dot{x}, \dot{y}, \dot{z}, t\right) \equiv T - U$$

$$T = \tfrac{1}{2}m\left(\dot{x}^2 + \dot{y}^2 + \dot{z}^2\right)$$

x-component: $\left(\frac{d}{dt}\frac{\partial L}{\partial \dot{x}} - \frac{\partial L}{\partial x}\right) = 0$

Note: Here we are using cartesian coordinates for convenience.

Apparently: $F_x = -\frac{\partial U}{\partial x} + \frac{d}{dt}\frac{\partial U}{\partial \dot{x}}$

Answer: $U = q\Phi\left(\mathbf{r},t\right) - \frac{q}{c}\dot{\mathbf{r}}\cdot\mathbf{A}\left(\mathbf{r},t\right)$

where $\mathbf{E}\left(\mathbf{r},t\right) = -\nabla\Phi\left(\mathbf{r},t\right) - \frac{1}{c}\frac{\partial \mathbf{A}\left(\mathbf{r},t\right)}{\partial t}$ $\mathbf{B}\left(\mathbf{r},t\right) = \nabla\times\mathbf{A}\left(\mathbf{r},t\right)$

Lorentz forces, continued:

$$x-\text{component of Lorentz force}: \; F_x = q\left(E_x + \tfrac{1}{c}(\mathbf{v}\times\mathbf{B})_x\right)$$

$$\text{Suppose}: \qquad U = q\Phi(\mathbf{r},t) - \frac{q}{c}\dot{\mathbf{r}}\cdot\mathbf{A}(\mathbf{r},t)$$

$$\text{Consider}: \quad F_x = -\frac{\partial U}{\partial x} + \frac{d}{dt}\frac{\partial U}{\partial \dot{x}}$$

$$-\frac{\partial U}{\partial x} = -q\frac{\partial \Phi(\mathbf{r},t)}{\partial x} + \frac{q}{c}\left(\dot{x}\frac{\partial A_x(\mathbf{r},t)}{\partial x} + \dot{y}\frac{\partial A_y(\mathbf{r},t)}{\partial x} + \dot{z}\frac{\partial A_z(\mathbf{r},t)}{\partial x}\right)$$

$$\frac{\partial U}{\partial \dot{x}} = -\frac{q}{c}A_x(\mathbf{r},t)$$

$$\frac{d}{dt}\frac{\partial U}{\partial \dot{x}} = -\frac{q}{c}\frac{dA_x(\mathbf{r},t)}{dt} = -\frac{q}{c}\left(\frac{\partial A_x(\mathbf{r},t)}{\partial x}\dot{x} + \frac{\partial A_x(\mathbf{r},t)}{\partial y}\dot{y} + \frac{\partial A_x(\mathbf{r},t)}{\partial z}\dot{z} + \frac{\partial A_x(\mathbf{r},t)}{\partial t}\right)$$

Lorentz forces, continued:

$$-\frac{\partial U}{\partial x} = -q\frac{\partial \Phi(\mathbf{r},t)}{\partial x} + \frac{q}{c}\left(\dot{x}\frac{\partial A_x(\mathbf{r},t)}{\partial x} + \dot{y}\frac{\partial A_y(\mathbf{r},t)}{\partial x} + \dot{z}\frac{\partial A_z(\mathbf{r},t)}{\partial x}\right)$$

$$\frac{d}{dt}\frac{\partial U}{\partial \dot{x}} = -\frac{q}{c}\left(\frac{\partial A_x(\mathbf{r},t)}{\partial x}\dot{x} + \frac{\partial A_x(\mathbf{r},t)}{\partial y}\dot{y} + \frac{\partial A_x(\mathbf{r},t)}{\partial z}\dot{z} + \frac{\partial A_x(\mathbf{r},t)}{\partial t}\right)$$

$$F_x = -\frac{\partial U}{\partial x} + \frac{d}{dt}\frac{\partial U}{\partial \dot{x}}$$

$$= -q\frac{\partial \Phi(\mathbf{r},t)}{\partial x} + \frac{q}{c}\dot{y}\left(\frac{\partial A_y(\mathbf{r},t)}{\partial x} - \frac{\partial A_x(\mathbf{r},t)}{\partial y}\right) + \frac{q}{c}\dot{z}\left(\frac{\partial A_z(\mathbf{r},t)}{\partial x} - \frac{\partial A_x(\mathbf{r},t)}{\partial y}\right) - \frac{q}{c}\frac{\partial A_x(\mathbf{r},t)}{\partial t}$$

$$= -q\frac{\partial \Phi(\mathbf{r},t)}{\partial x} - \frac{q}{c}\frac{\partial A_x(\mathbf{r},t)}{\partial t} + \frac{q}{c}\dot{y}\left(\frac{\partial A_y(\mathbf{r},t)}{\partial x} - \frac{\partial A_x(\mathbf{r},t)}{\partial y}\right) + \frac{q}{c}\dot{z}\left(\frac{\partial A_z(\mathbf{r},t)}{\partial x} - \frac{\partial A_x(\mathbf{r},t)}{\partial z}\right)$$

$$= qE_x(\mathbf{r},t) + \frac{q}{c}\left(\dot{y}B_z(\mathbf{r},t) - \dot{z}B_y(\mathbf{r},t)\right) = qE_x(\mathbf{r},t) + \frac{q}{c}\left(\mathbf{v}\times\mathbf{B}(\mathbf{r},t)\right)_x$$

Some details on last step:

$$F_x = -\frac{\partial U}{\partial x} + \frac{d}{dt}\frac{\partial U}{\partial \dot{x}}$$

$$= -q\frac{\partial \Phi(\mathbf{r},t)}{\partial x} + \frac{q}{c}\dot{y}\left(\frac{\partial A_y(\mathbf{r},t)}{\partial x} - \frac{\partial A_x(\mathbf{r},t)}{\partial y}\right) + \frac{q}{c}\dot{z}\left(\frac{\partial A_z(\mathbf{r},t)}{\partial x} - \frac{\partial A_x(\mathbf{r},t)}{\partial y}\right) - \frac{q}{c}\frac{\partial A_x(\mathbf{r},t)}{\partial t}$$

$$= -q\frac{\partial \Phi(\mathbf{r},t)}{\partial x} - \frac{q}{c}\frac{\partial A_x(\mathbf{r},t)}{\partial t} + \frac{q}{c}\dot{y}\left(\frac{\partial A_y(\mathbf{r},t)}{\partial x} - \frac{\partial A_x(\mathbf{r},t)}{\partial y}\right) + \frac{q}{c}\dot{z}\left(\frac{\partial A_z(\mathbf{r},t)}{\partial x} - \frac{\partial A_x(\mathbf{r},t)}{\partial z}\right)$$

Note that: $\mathbf{E}(\mathbf{r},t) = -\nabla\Phi(\mathbf{r},t) - \frac{1}{c}\frac{\partial \mathbf{A}(\mathbf{r},t)}{\partial t}$ $\quad\quad$ $\mathbf{B}(\mathbf{r},t) = \nabla \times \mathbf{A}(\mathbf{r},t)$

So that:

$$F_x(\mathbf{r},t) \quad = qE_x(\mathbf{r},t) + \frac{q}{c}\left(\dot{y}B_z(\mathbf{r},t) - \dot{z}B_y(\mathbf{r},t)\right) = qE_x(\mathbf{r},t) + \frac{q}{c}\left(\mathbf{v}\times\mathbf{B}(\mathbf{r},t)\right)_x$$

Lorentz forces, continued:

Summary of results (using cartesian coordinates)

$$L = L(x, y, z, \dot{x}, \dot{y}, \dot{z}, t) \equiv T - U$$

$$T = \tfrac{1}{2} m\left(\dot{x}^2 + \dot{y}^2 + \dot{z}^2\right) \qquad U = q\Phi(\mathbf{r},t) - \frac{q}{c}\dot{\mathbf{r}} \cdot \mathbf{A}(\mathbf{r},t)$$

where $\quad \mathbf{E}(\mathbf{r},t) = -\nabla\Phi(\mathbf{r},t) - \frac{1}{c}\frac{\partial \mathbf{A}(\mathbf{r},t)}{\partial t} \qquad \mathbf{B}(\mathbf{r},t) = \nabla \times \mathbf{A}(\mathbf{r},t)$

$$L = \tfrac{1}{2} m\left(\dot{x}^2 + \dot{y}^2 + \dot{z}^2\right) - q\Phi(\mathbf{r},t) + \frac{q}{c}\dot{\mathbf{r}} \cdot \mathbf{A}(\mathbf{r},t)$$

Example Lorentz force

$$L = \tfrac{1}{2} m\left(\dot{x}^2 + \dot{y}^2 + \dot{z}^2\right) - q\Phi(\mathbf{r},t) + \frac{q}{c}\dot{\mathbf{r}}\cdot\mathbf{A}(\mathbf{r},t)$$

Suppose $\mathbf{E}(\mathbf{r},t) \equiv 0, \quad \mathbf{B}(\mathbf{r},t) \equiv B_0\hat{\mathbf{z}}$

$$\mathbf{A}(\mathbf{r},t) = \tfrac{1}{2} B_0\left(-y\hat{\mathbf{x}} + x\hat{\mathbf{y}}\right)$$

$$L = \tfrac{1}{2} m\left(\dot{x}^2 + \dot{y}^2 + \dot{z}^2\right) + \frac{q}{2c} B_0\left(-\dot{x}y + \dot{y}x\right)$$

$$\frac{d}{dt}\frac{\partial L}{\partial \dot{x}} - \frac{\partial L}{\partial x} = 0 \qquad \Rightarrow \frac{d}{dt}\left(m\dot{x} - \frac{q}{2c}B_0 y\right) - \frac{q}{2c}B_0\dot{y} = 0$$

$$\frac{d}{dt}\frac{\partial L}{\partial \dot{y}} - \frac{\partial L}{\partial y} = 0 \qquad \Rightarrow \frac{d}{dt}\left(m\dot{y} + \frac{q}{2c}B_0 x\right) + \frac{q}{2c}B_0\dot{x} = 0$$

$$\frac{d}{dt}\frac{\partial L}{\partial \dot{z}} - \frac{\partial L}{\partial z} = 0 \qquad \Rightarrow \frac{d}{dt}m\dot{z} = 0$$

Example Lorentz force -- continued

$$L = \tfrac{1}{2} m\left(\dot{x}^2 + \dot{y}^2 + \dot{z}^2\right) + \frac{q}{2c} B_0\left(-\dot{x}y + \dot{y}x\right)$$

$$\frac{d}{dt}\left(m\dot{x} - \frac{q}{2c} B_0 y\right) - \frac{q}{2c} B_0 \dot{y} = 0 \qquad \Rightarrow m\ddot{x} - \frac{q}{c} B_0 \dot{y} = 0$$

$$\frac{d}{dt}\left(m\dot{y} + \frac{q}{2c} B_0 x\right) + \frac{q}{2c} B_0 \dot{x} = 0 \qquad \Rightarrow m\ddot{y} + \frac{q}{c} B_0 \dot{x} = 0$$

$$\frac{d}{dt} m\dot{z} = 0 \qquad \Rightarrow m\ddot{z} = 0$$

Example Lorentz force -- continued

$$L = \tfrac{1}{2} m\left(\dot{x}^2 + \dot{y}^2 + \dot{z}^2\right) + \frac{q}{2c} B_0\left(-\dot{x}y + \dot{y}x\right)$$

$$m\ddot{x} = +\frac{q}{c} B_0 \dot{y}$$

$$m\ddot{y} = -\frac{q}{c} B_0 \dot{x}$$

$$m\ddot{z} = 0$$

Note that same equations are obtained from direct application of Newton's laws:

$$m\ddot{\mathbf{r}} = \frac{q}{c}\dot{\mathbf{r}} \times B_0 \hat{\mathbf{z}}$$

Example Lorentz force -- continued

Evaluation of equations:

$$m\ddot{x} - \frac{q}{c} B_0 \dot{y} = 0 \qquad \dot{x}(t) = V_0 \sin\left(\frac{qB_0}{mc} t + \phi\right)$$

$$m\ddot{y} + \frac{q}{c} B_0 \dot{x} = 0 \qquad \dot{y}(t) = V_0 \cos\left(\frac{qB_0}{mc} t + \phi\right)$$

$$m\ddot{z} = 0 \qquad \dot{z}(t) = V_{0z}$$

$$x(t) = x_0 - \frac{mc}{qB_0} V_0 \cos\left(\frac{qB_0}{mc} t + \phi\right)$$

$$y(t) = y_0 + \frac{mc}{qB_0} V_0 \sin\left(\frac{qB_0}{mc} t + \phi\right)$$

$$z(t) = z_0 + V_{0z} t$$

Example Lorentz force -- continued

Consider formulation with different Gauge: $\mathbf{A}(\mathbf{r}) = -B_0 y \hat{\mathbf{x}}$

$$L = \tfrac{1}{2} m\left(\dot{x}^2 + \dot{y}^2 + \dot{z}^2\right) - \frac{q}{c} B_0 \dot{x} y$$

$$\frac{d}{dt}\left(m\dot{x} - \frac{q}{c} B_0 y \right) = 0 \qquad \Rightarrow m\ddot{x} - \frac{q}{c} B_0 \dot{y} = 0$$

$$\frac{d}{dt}(m\dot{y}) + \frac{q}{c} B_0 \dot{x} = 0 \qquad \Rightarrow m\ddot{y} + \frac{q}{c} B_0 \dot{x} = 0$$

$$\frac{d}{dt} m\dot{z} = 0 \qquad \Rightarrow m\ddot{z} = 0$$

Does it surprise you that the same equations of motion are obtained with a different Gauge?

Now consider formulation of motion with constraints --

Comments on generalized coordinates:

$$L = L(\{q_\sigma(t)\}, \{\dot{q}_\sigma(t)\}, t)$$

$$\frac{d}{dt}\frac{\partial L}{\partial \dot{q}_\sigma} - \frac{\partial L}{\partial q_\sigma} = 0$$

Here we have assumed that the generalized coordinates q_σ are independent. Now consider the possibility that the coordinates are related through constraint equations of the form:

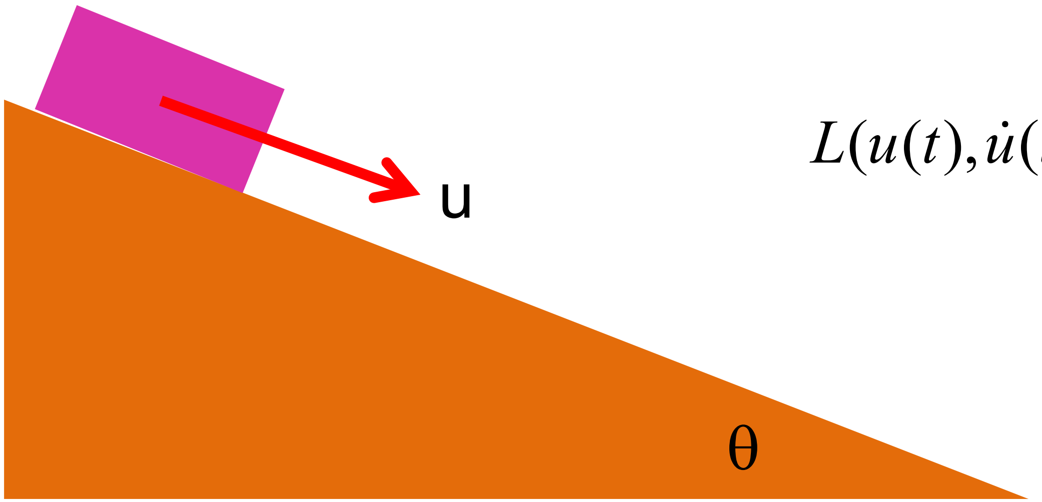
Lagrange multipliers

$$\text{Lagrangian}: \quad L = L(\{q_\sigma(t)\}, \{\dot{q}_\sigma(t)\}, t)$$

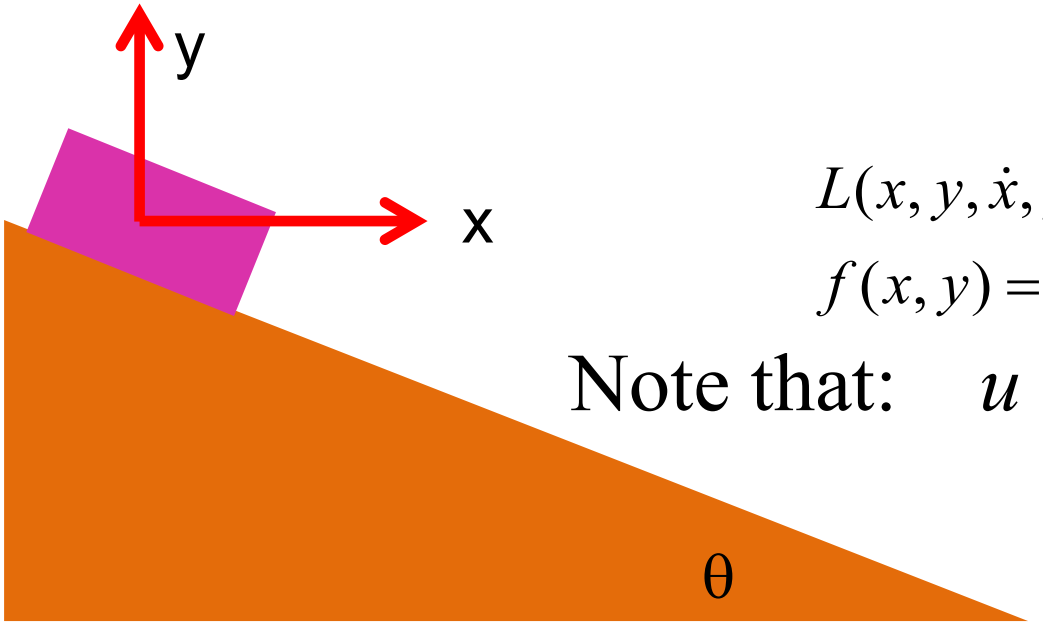
$$\text{Constraints}: \quad f_j = f_j(\{q_\sigma(t)\}, t) = 0$$

$$\text{Modified Euler-Lagrange equations}: \quad \frac{d}{dt}\frac{\partial L}{\partial \dot{q}_\sigma} - \frac{\partial L}{\partial q_\sigma} + \sum_j \lambda_j \frac{\partial f_j}{\partial q_\sigma} = 0$$

Simple example:



$$L(u(t),\dot{u}(t)) = \tfrac{1}{2} m\dot{u}^2 + mgu\sin\theta$$



$$L(x,y,\dot{x},\dot{y}) = \tfrac{1}{2} m\left(\dot{x}^2 + \dot{y}^2\right) - mgy$$

$$f(x,y) = \sin\theta\ x + \cos\theta\ y = 0$$

Note that: $u = x\cos\theta - y\sin\theta$

Case 1:

$$L(u(t),\dot{u}(t)) = \tfrac{1}{2}m\dot{u}^2 + mgu\sin\theta$$

$$\frac{d}{dt}\frac{\partial L}{\partial \dot{u}} - \frac{\partial L}{\partial u} = 0 = m\ddot{u} - mg\sin\theta = 0$$

$$\Rightarrow \ddot{u} = g\sin\theta$$

Case 2:

$$L(x,y,\dot{x},\dot{y}) = \tfrac{1}{2}m\left(\dot{x}^2+\dot{y}^2\right) - mgy$$

$$f(x,y) = \sin\theta\; x + \cos\theta\; y = 0$$

$$\frac{d}{dt}\frac{\partial L}{\partial \dot{x}} - \frac{\partial L}{\partial x} + \lambda\frac{\partial f}{\partial x} = 0 = m\ddot{x} + \lambda\sin\theta$$

$$\frac{d}{dt}\frac{\partial L}{\partial \dot{y}} - \frac{\partial L}{\partial y} + \lambda\frac{\partial f}{\partial y} = 0 = m\ddot{y} + mg + \lambda\cos\theta$$

$$\sin\theta\; \ddot{x} + \cos\theta\; \ddot{y} = 0$$

$$\Rightarrow \lambda = -mg\cos\theta$$

Force of constraint; normal to incline

$$\left(\cos\theta\; \ddot{x} - \sin\theta\; \ddot{y}\right) = g\sin\theta$$

Which method would you use to solve the problem?

Case 1

Case 2

Rational for Lagrange multipliers

Recall Hamilton's principle:

$$S = \int_{t_i}^{t_f} L\left(\{q_\sigma(t)\},\{\dot{q}_\sigma(t)\},t\right)dt$$

$$\delta S = 0 = \int_{t_i}^{t_f} \left(\sum_\sigma \left(\frac{d}{dt}\frac{\partial L}{\partial \dot{q}_\sigma} - \frac{\partial L}{\partial q_\sigma} \right) \delta q_\sigma \right) dt$$

With constraints: $f_j = f_j\left(\{q_\sigma(t)\},t\right) = 0$

Variations δq_σ are no longer independent.

$$\delta f_j = 0 = \sum_\sigma \frac{\partial f_j}{\partial q_\sigma}\delta q_\sigma \quad \text{at each } t$$

$\Rightarrow$ Add 0 to Euler-Lagrange equations in the form:

$$\sum_j \lambda_j \sum_\sigma \frac{\partial f_j}{\partial q_\sigma}\delta q_\sigma$$

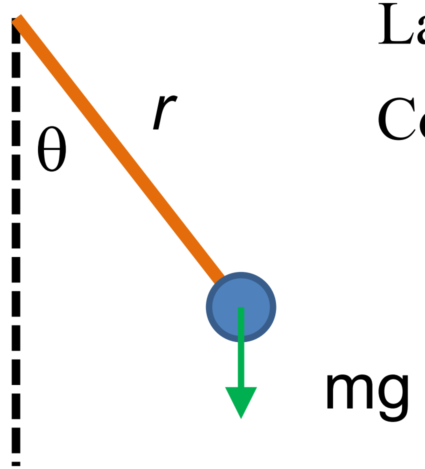
Euler-Lagrange equations with constraints:

$$\text{Lagrangian}: \quad L = L\left(\{q_\sigma(t)\}, \{\dot{q}_\sigma(t)\}, t\right)$$

$$\text{Constraints}: \quad f_j = f_j\left(\{q_\sigma(t)\}, t\right) = 0$$

$$\text{Modified Euler-Lagrange equations}: \quad \frac{d}{dt}\frac{\partial L}{\partial \dot{q}_\sigma} - \frac{\partial L}{\partial q_\sigma} + \sum_j \lambda_j \frac{\partial f_j}{\partial q_\sigma} = 0$$

Example:



$$\text{Lagrangian}: \quad L = \tfrac{1}{2} m\left(\dot{r}^2 + r^2\dot{\theta}^2\right) + mgr\cos\theta$$

$$\text{Constraints}: \quad f = r - \ell = 0$$

Example continued:

$$\text{Lagrangian}: \quad L = \tfrac{1}{2} m\left(\dot{r}^2 + r^2\dot{\theta}^2\right) + mgr\cos\theta$$

$$\text{Constraints}: \quad f = r - \ell = 0$$

$$\frac{d}{dt} m\dot{r} - mr\dot{\theta}^2 - mg\cos\theta + \lambda = 0$$

$$\frac{d}{dt} mr^2\dot{\theta} + mgr\sin\theta = 0$$

$$\dot{r} = 0 = \ddot{r} \qquad\qquad r = \ell$$

$$\Rightarrow \quad \ddot{\theta} = -\frac{g}{\ell}\sin\theta$$

$$\Rightarrow \quad \lambda = m\ell\dot{\theta}^2 + mg\cos\theta$$

Another example:

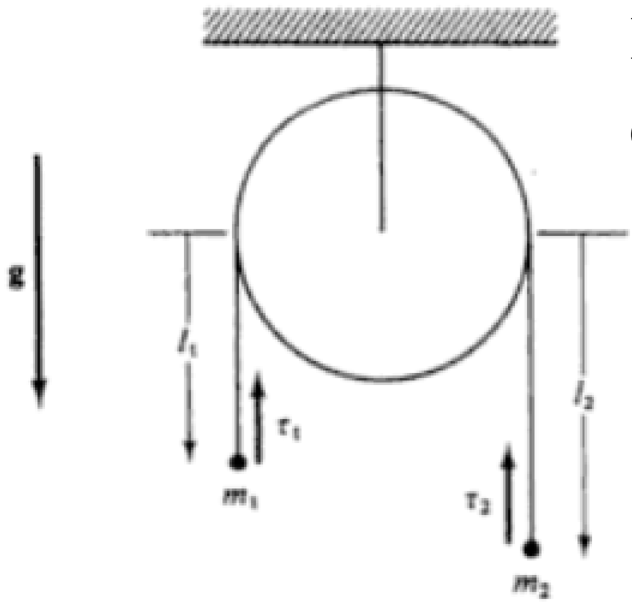


Figure 19.1 Atwood's machine.

Lagrangian: $L = \frac{1}{2} m_1 \dot{\ell}_1^2 + \frac{1}{2} m_2 \dot{\ell}_2^2 + m_1 g \ell_1 + m_2 g \ell_2$

Constraints: $f = \ell_1 + \ell_2 - \ell = 0$

$$\frac{d}{dt} m_1 \dot{\ell}_1 - m_1 g + \lambda = 0$$

$$\frac{d}{dt} m_2 \dot{\ell}_2 - m_2 g + \lambda = 0$$

$$\dot{\ell}_1 + \dot{\ell}_2 = 0 = \ddot{\ell}_1 + \ddot{\ell}_2$$

$$\Rightarrow \lambda = \frac{2 m_1 m_2}{m_1 + m_2} g$$

$$\ddot{\ell}_1 = -\ddot{\ell}_2 = \frac{m_1 - m_2}{m_1 + m_2} g$$