Lecture 16
Thur. 10.18.2012

Introducing GCC Lagrangian `a la Trebuchet Dynamics

(Ch. 1-3 of Unit 2 and Unit 3)

The trebuchet (or ingenium) and its cultural relevancy (3000 BCE to 21st See Sci. Am. ***273****, 66 (July 1995))*
- *The medieval ingenium (9th to 14th century) and modern re-enactments*
- *Human kinesthetics and sports kinesiology*

Cartesian to GCC transformations (Mostly Unit 2.)
- *Jacobian relations*
- *Kinetic energy calculation*
- *Dynamic metric tensor γ_{mn}*

Geometric and topological properties of GCC transformations (Mostly Unit 3.)
- *Multivalued functionality and connections*
- *Covariant and contravariant relations*
- *Metric tensors*

Chapter 1. The Trebuchet: A dream problem for Galileo?

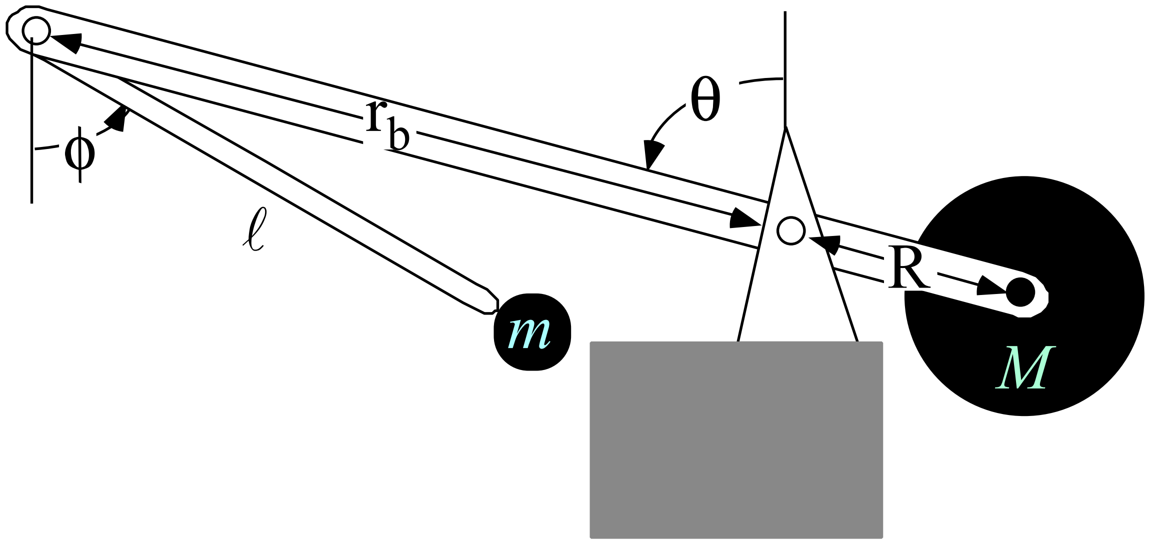
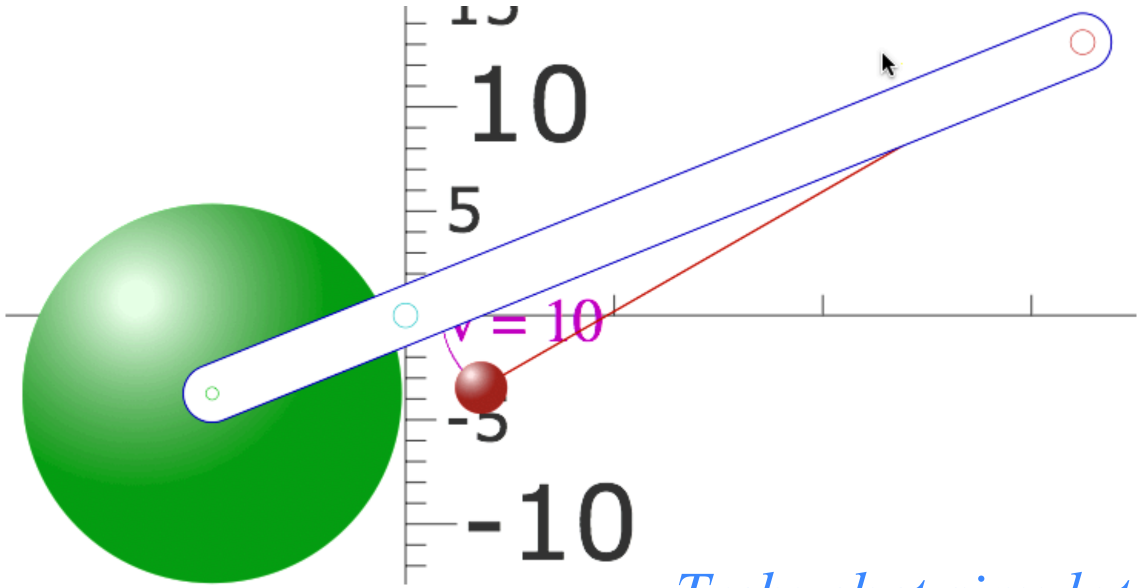


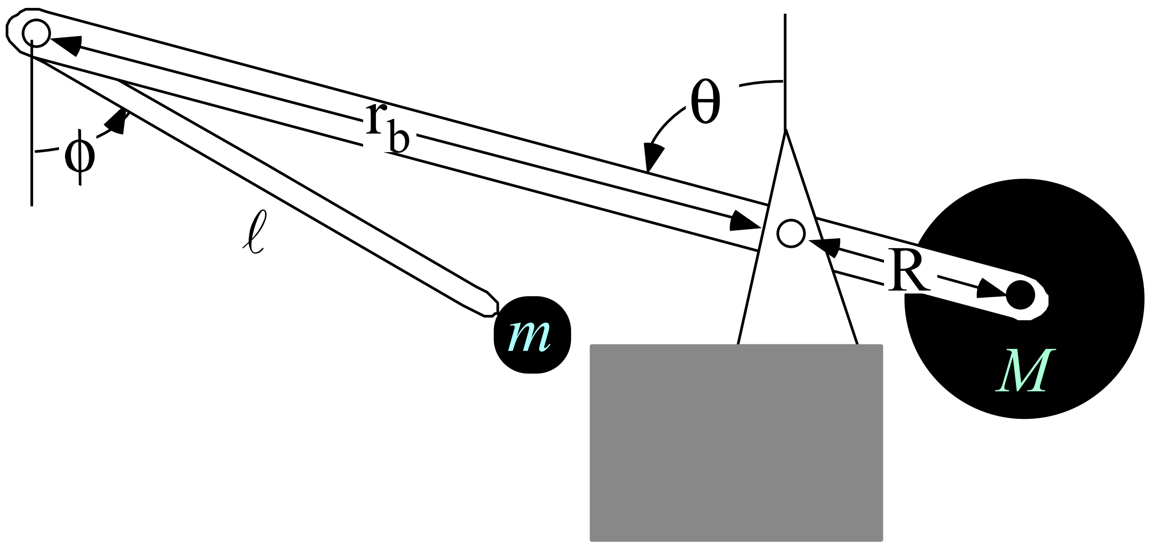
Fig. 2.1.1 An elementary ground-fixed trebuchet



Trebuchet simulator

http://www.uark.edu/rso/modphys/testing/markup/TrebuchetWeb.html

Chapter 1. The Trebuchet: A dream problem for Galileo?



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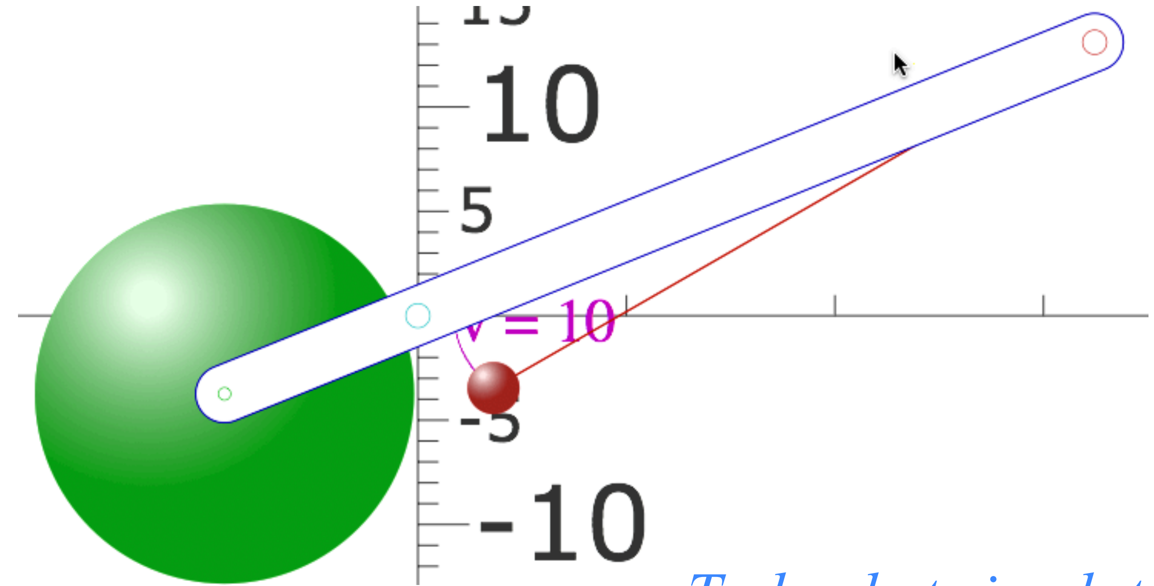

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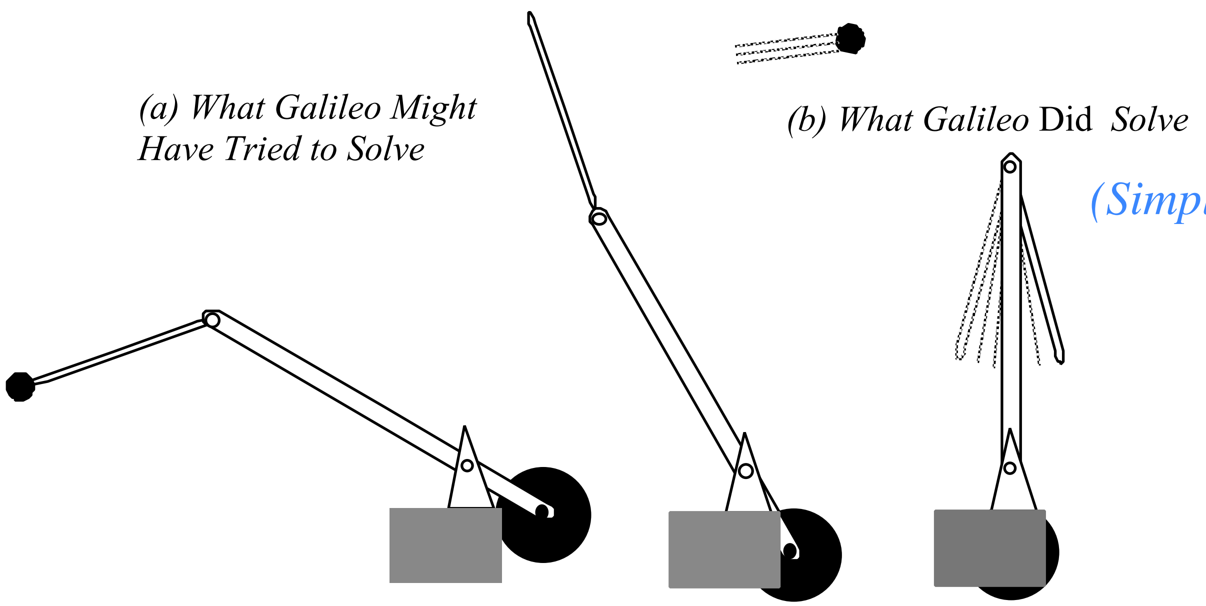
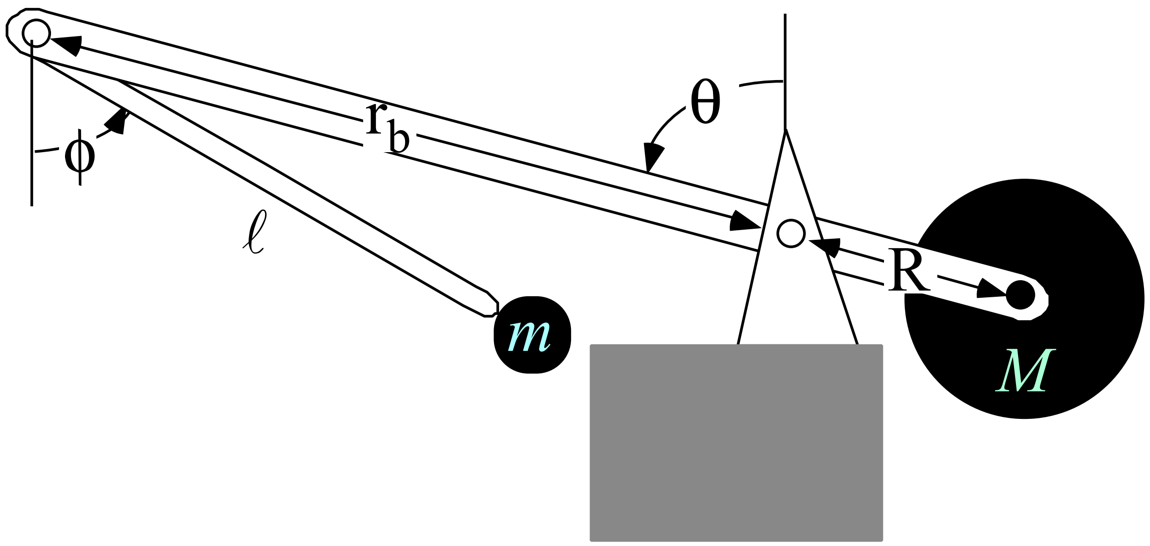


(Simple pendulum dynamics)

Fig. 2.1.2 Galileo's (supposed fictitious) problem

Chapter 1. The Trebuchet: A dream problem for Galileo?



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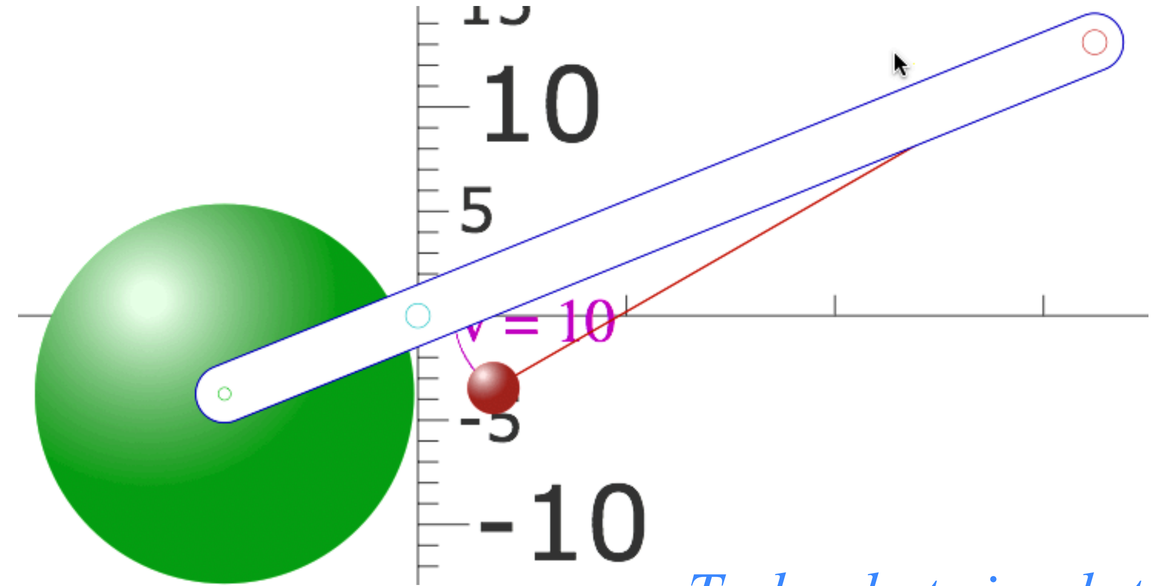

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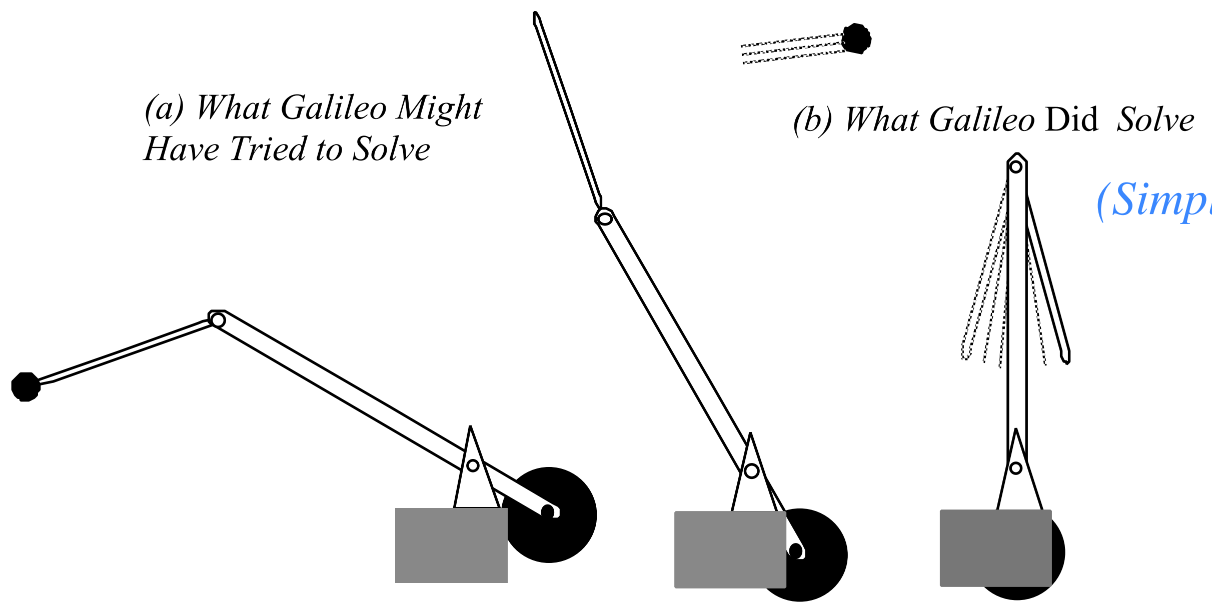

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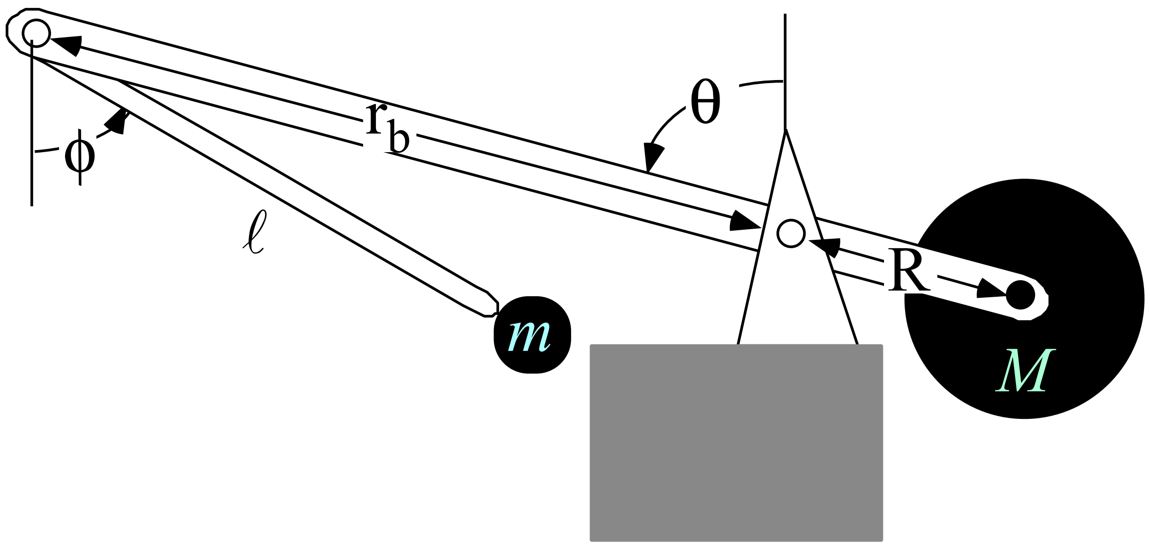

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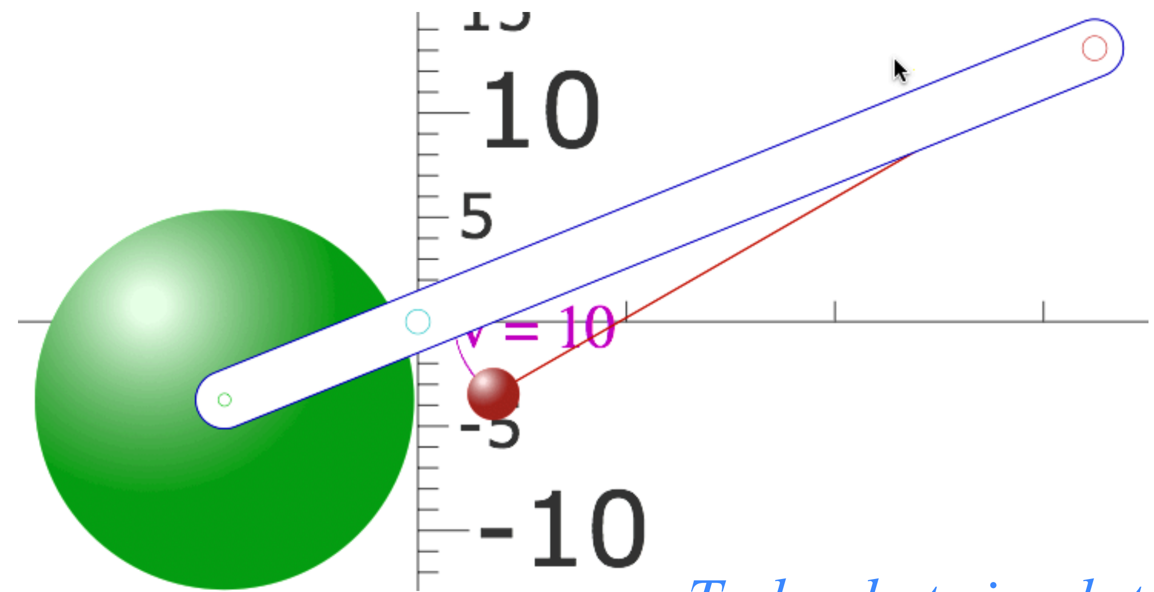

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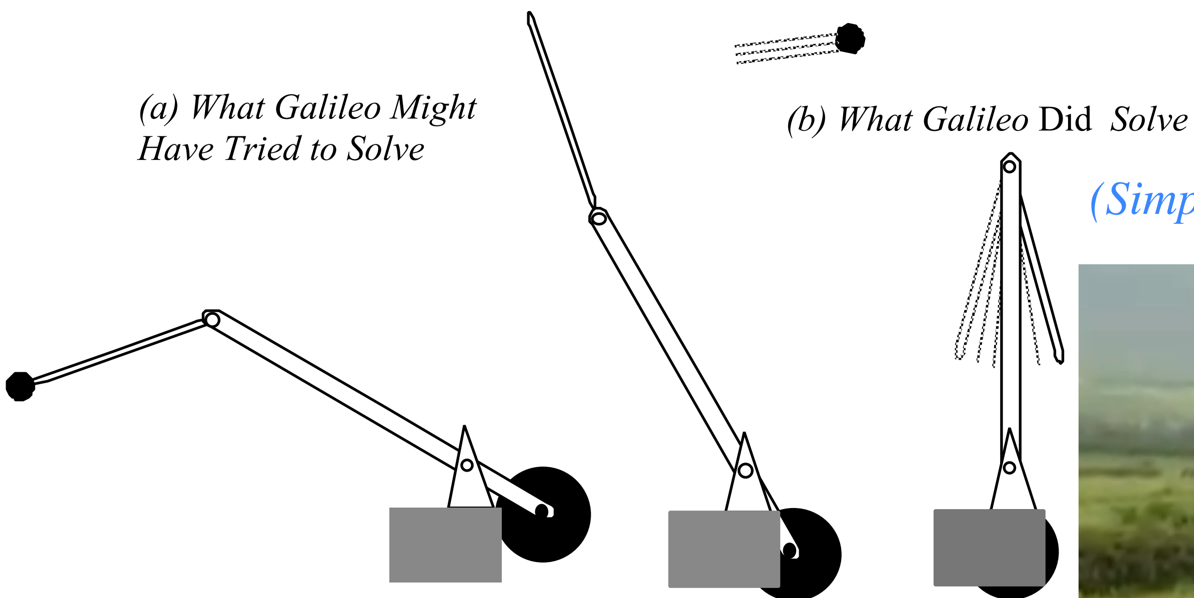

Fig. 2.1.2 Galileo's (supposed) problem

(Simple pendulum dynamics)

The trebuchet (or ingenium) and its cultural relevancy (3000 BCE to 21st See Sci. Am. ***273****, 66 (July 1995))*

The medieval ingenium (9th to 14th century) and modern re-enactments

→ *Human kinesthetics and sports kinesiology* *(a) Early Human Agriculture and Infrastructure Building Activity*

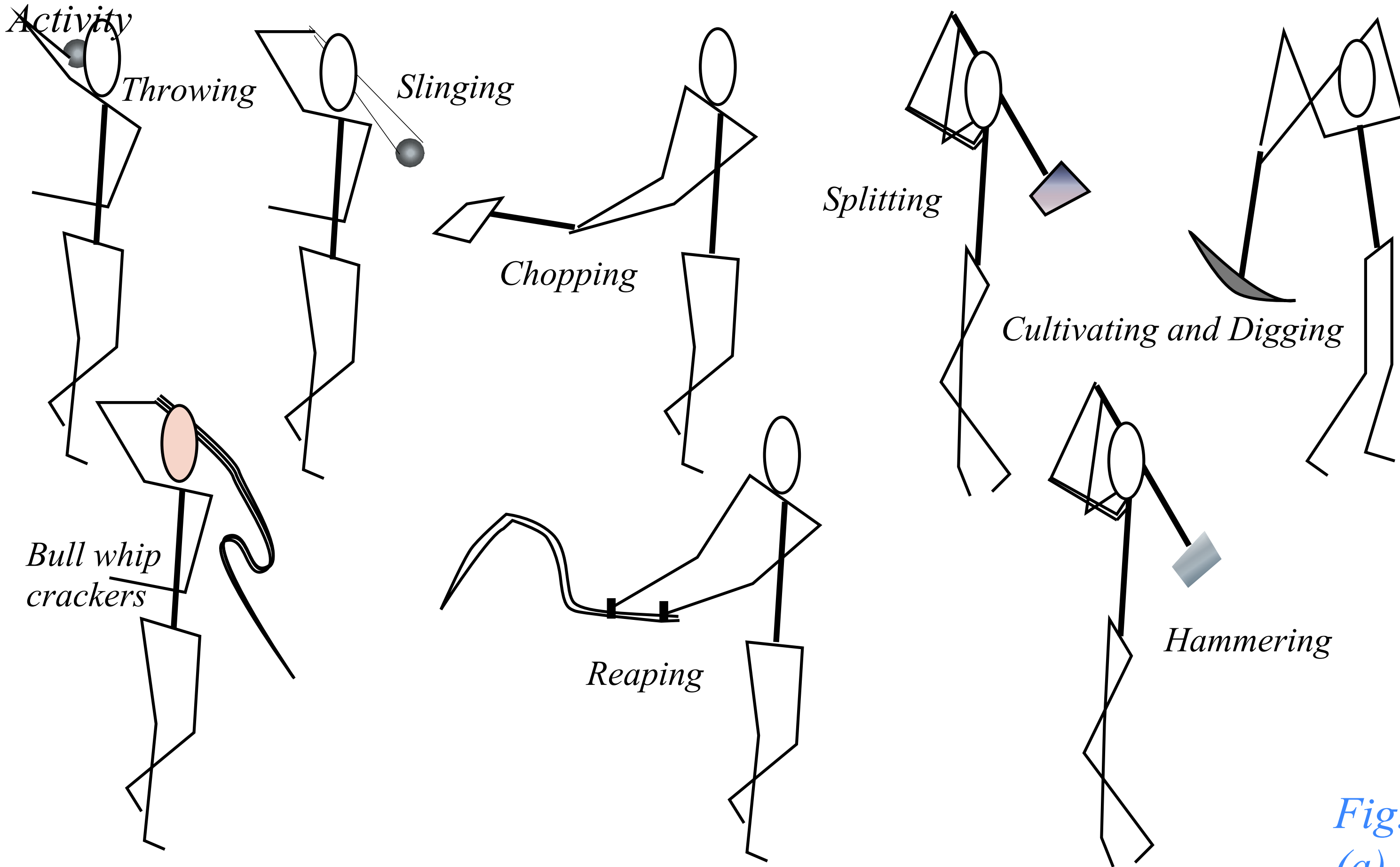

Fig. 2.1.3 Trebuchet-like motion of humans. (a) Early work.

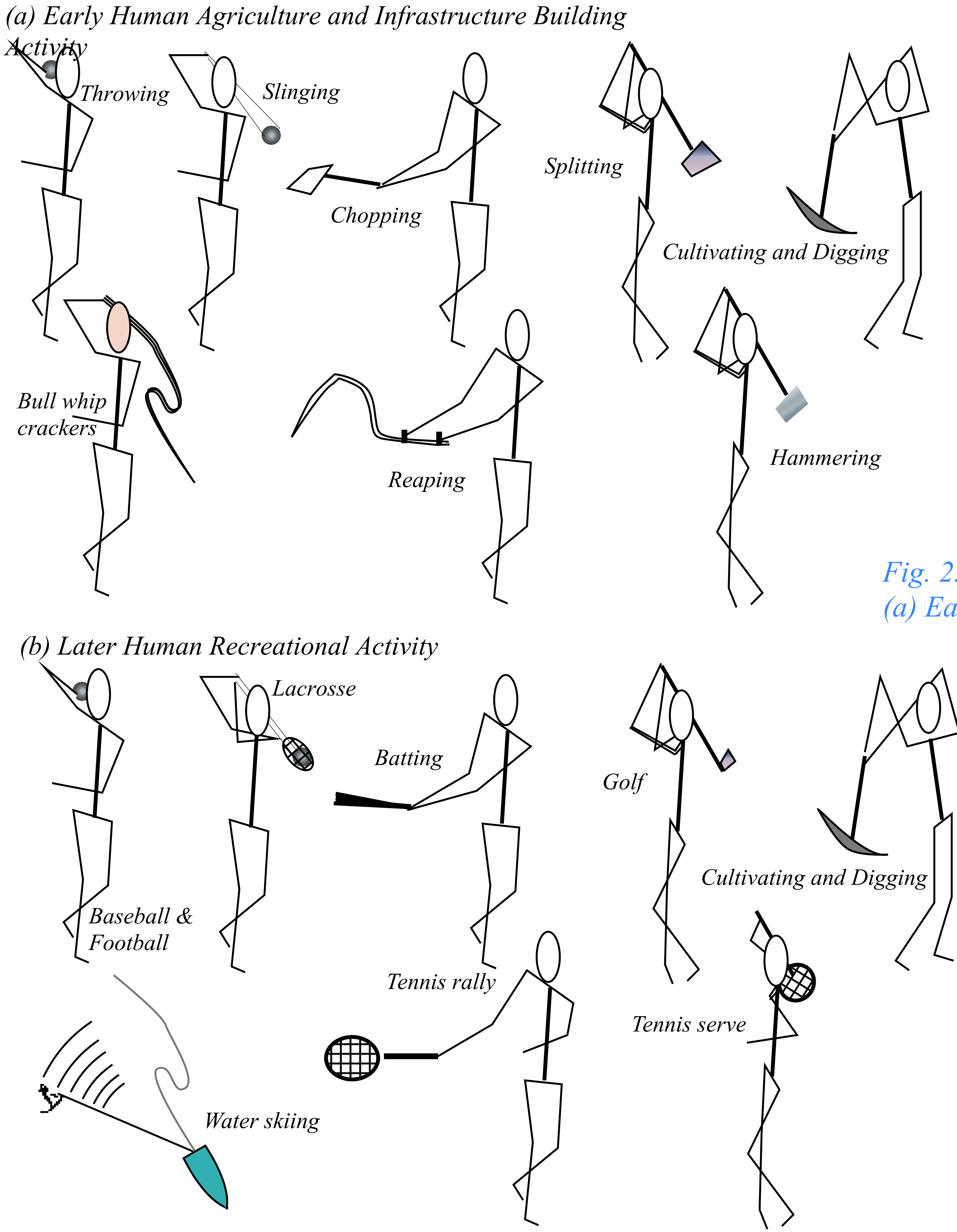

Fig. 2.1.3 Trebuchet-like motion of humans.
(a) Early work. (b) Later recreational kinesthetics.

Cartesian to GCC transformations

→ *Jacobian relations*

Kinetic energy calculation

Dynamic metric tensor γ_{mn}

Coordinates of mass M (Driving weight):

Coordinates of mass m (Payload or projectile):

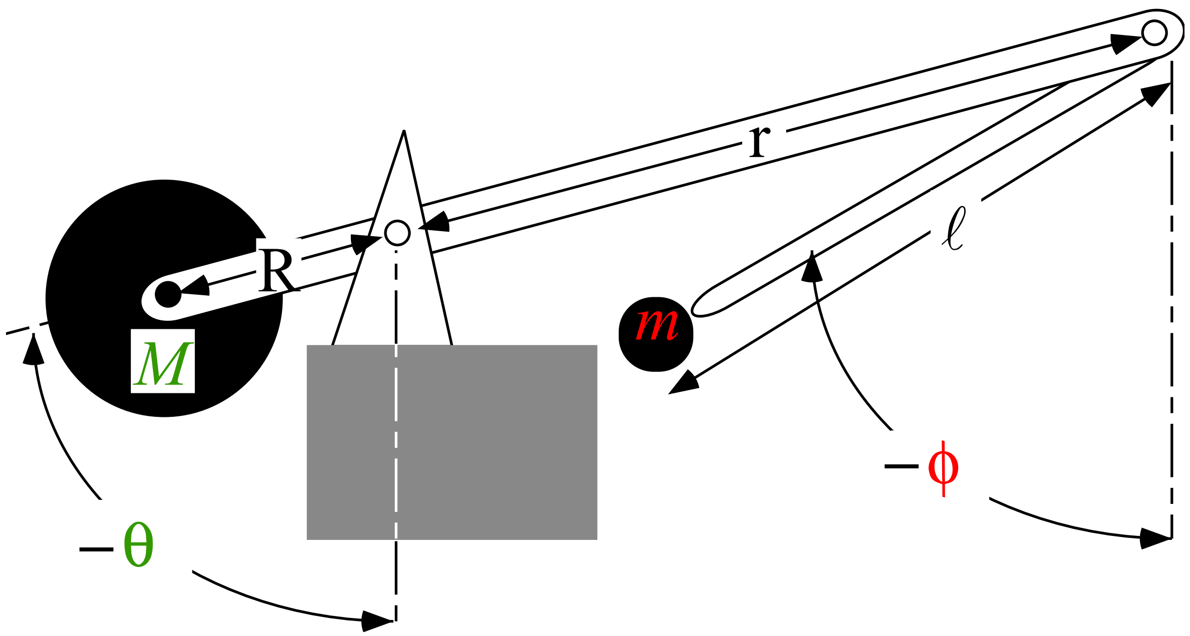

Fig. 2.2.1 Cartesian coordinates related to trebuchet angles θ and φ.

Coordinates of mass M (Driving weight):

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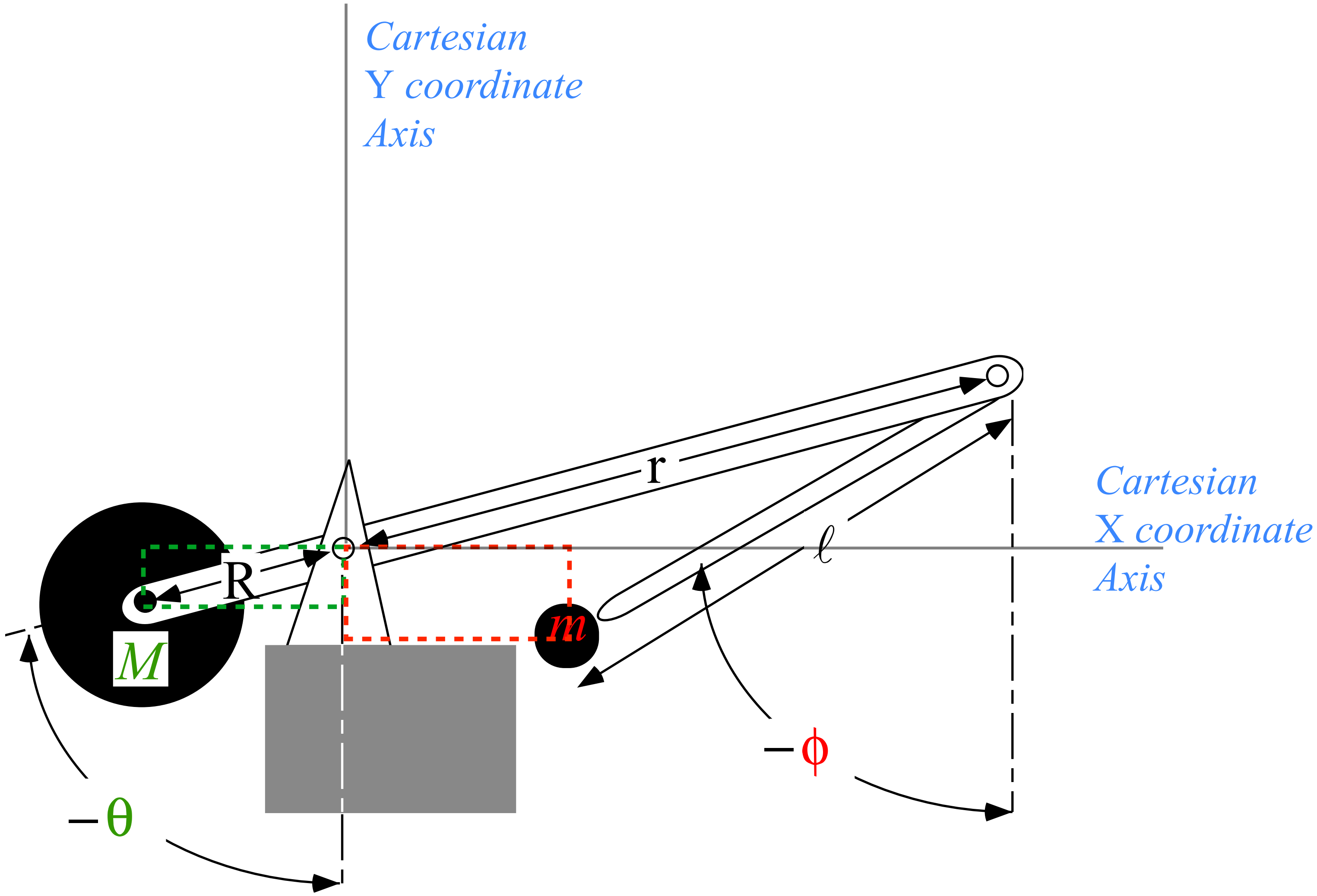

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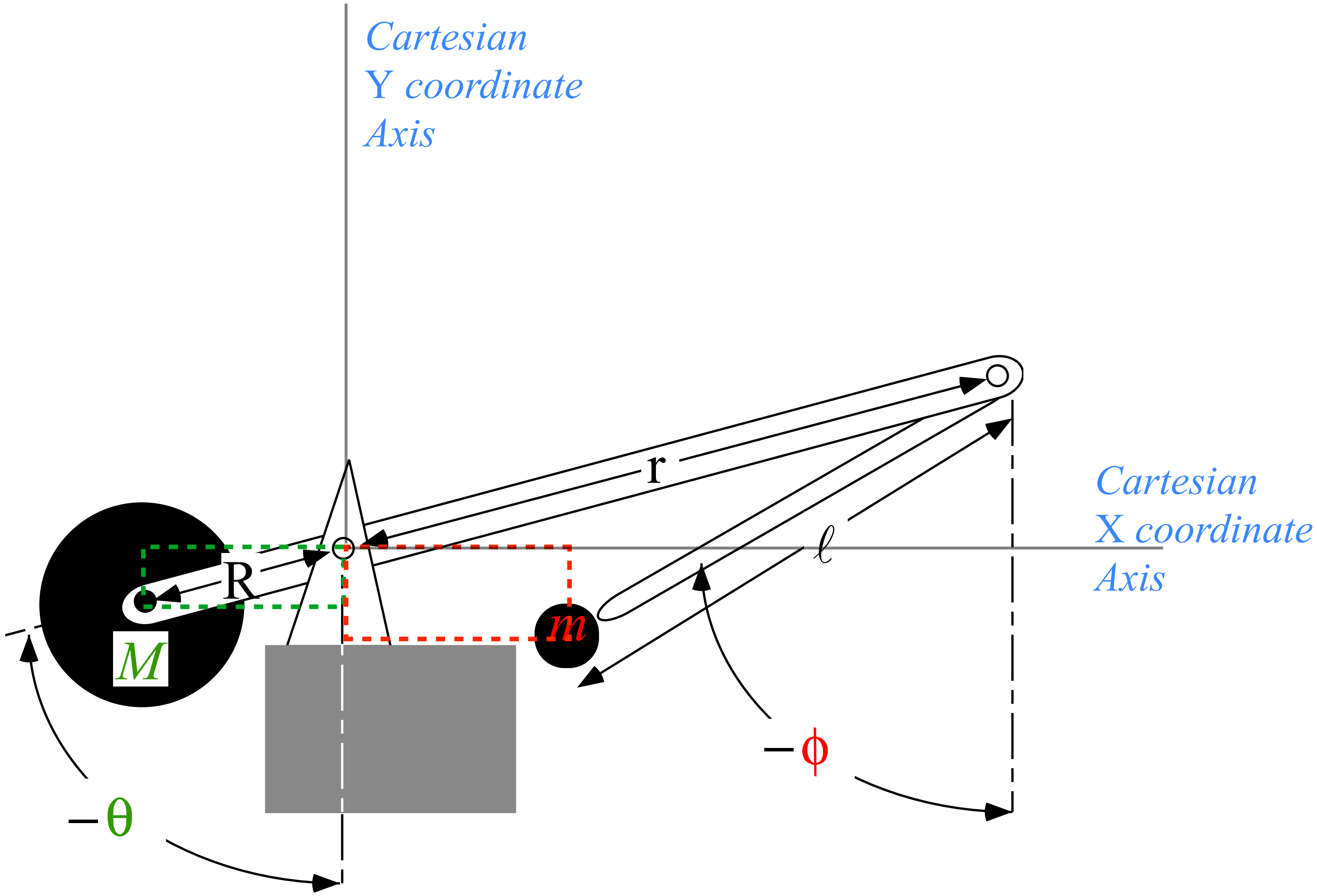

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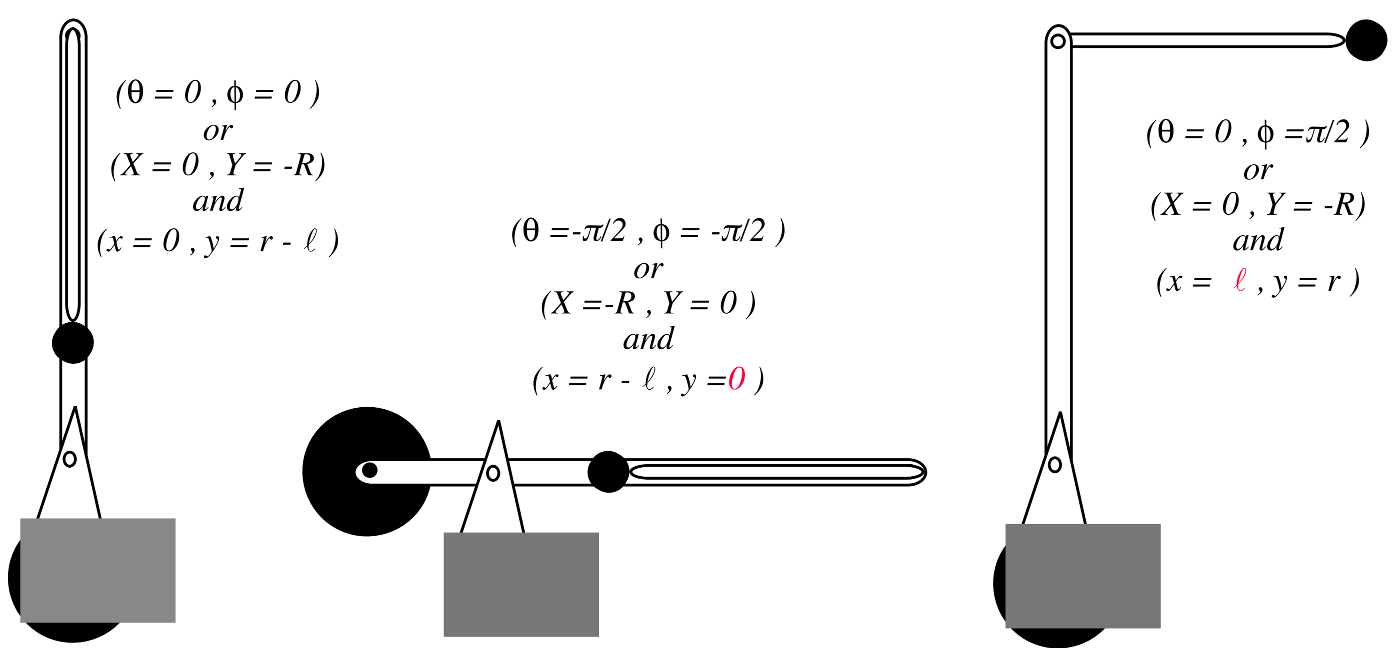
Fig. 2.2.2 Singular positions of the trebuchet



Coordinates of mass *M (Driving weight)*:

$X = R \sin\theta$

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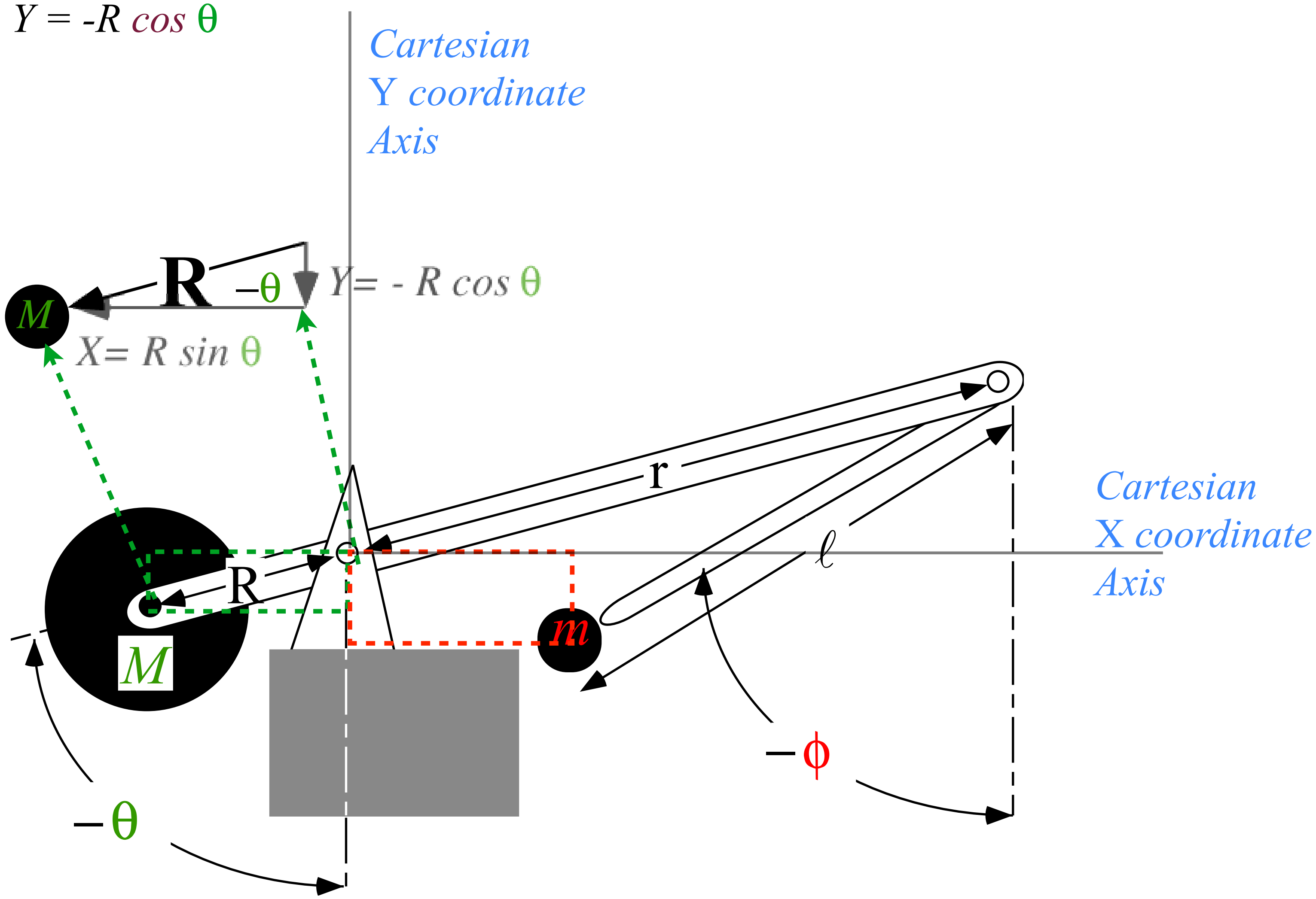

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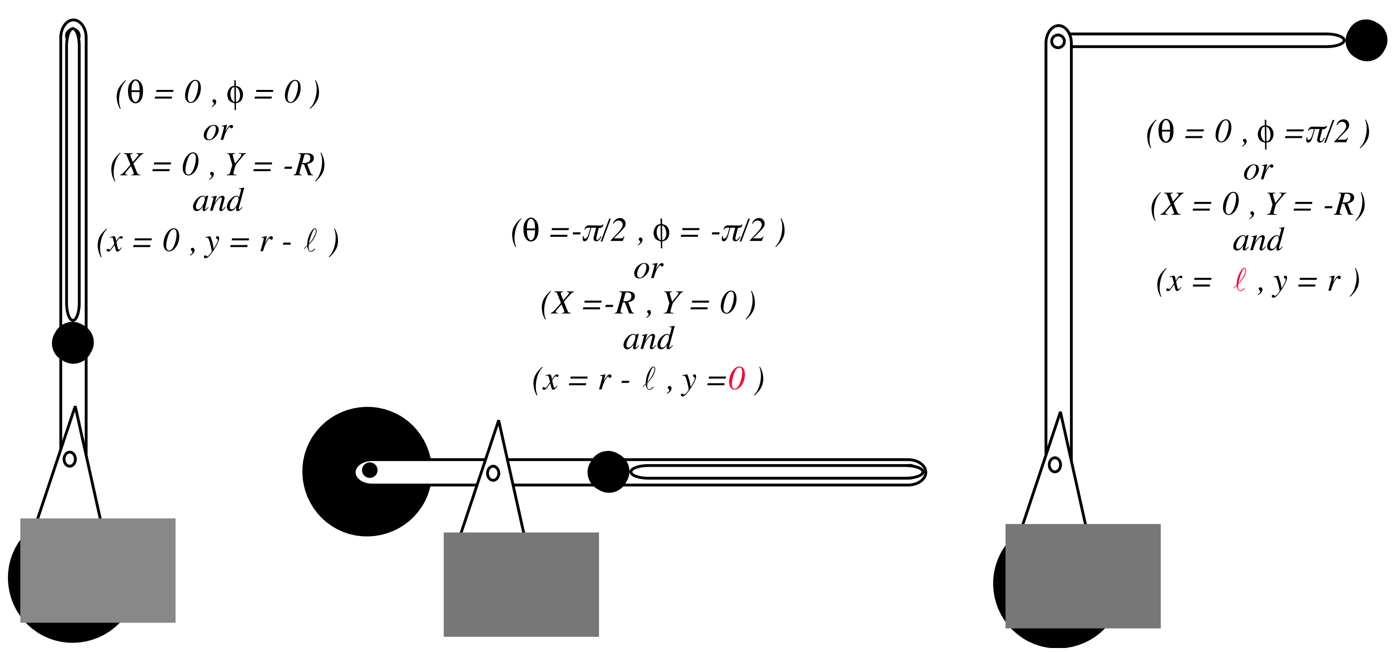

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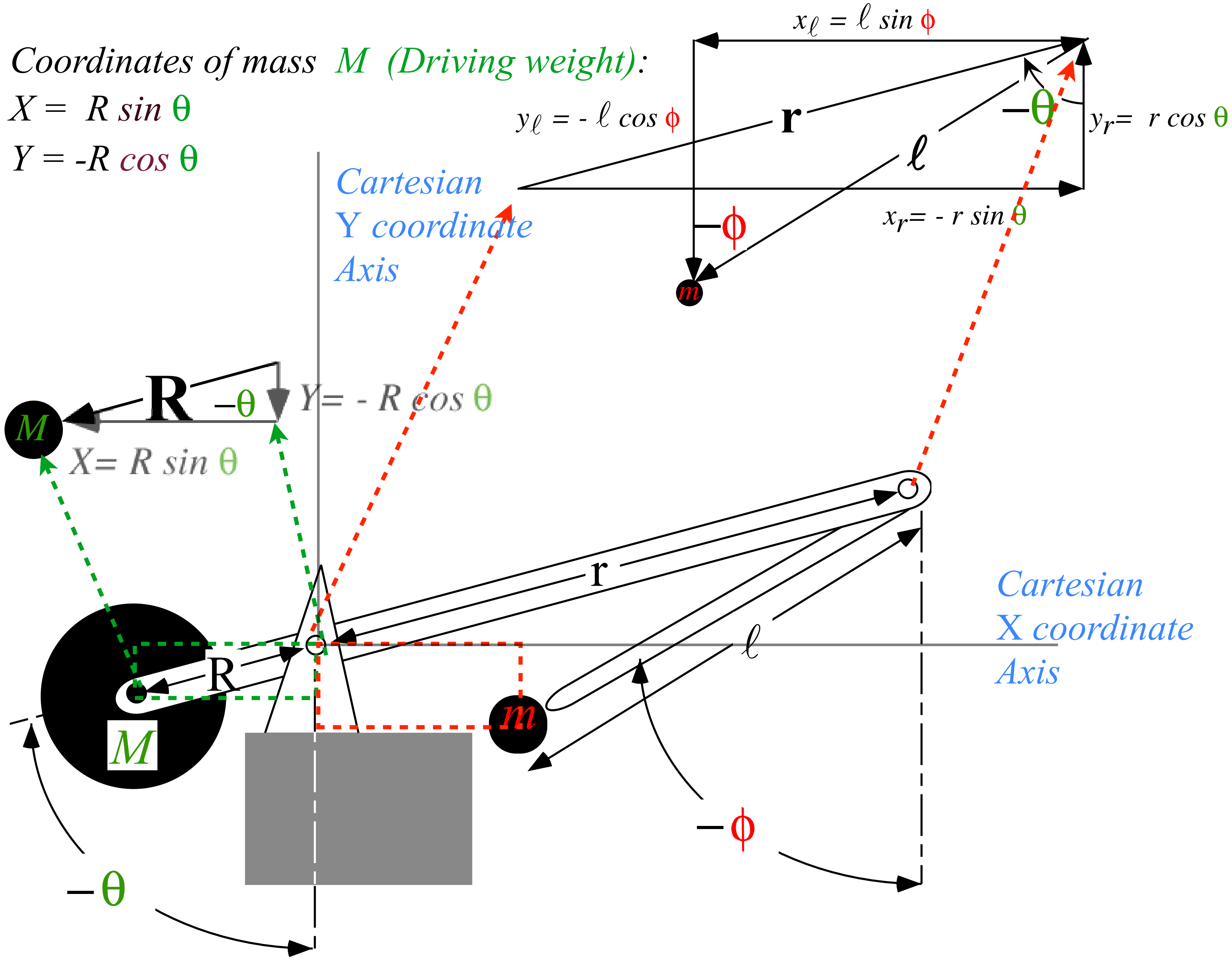

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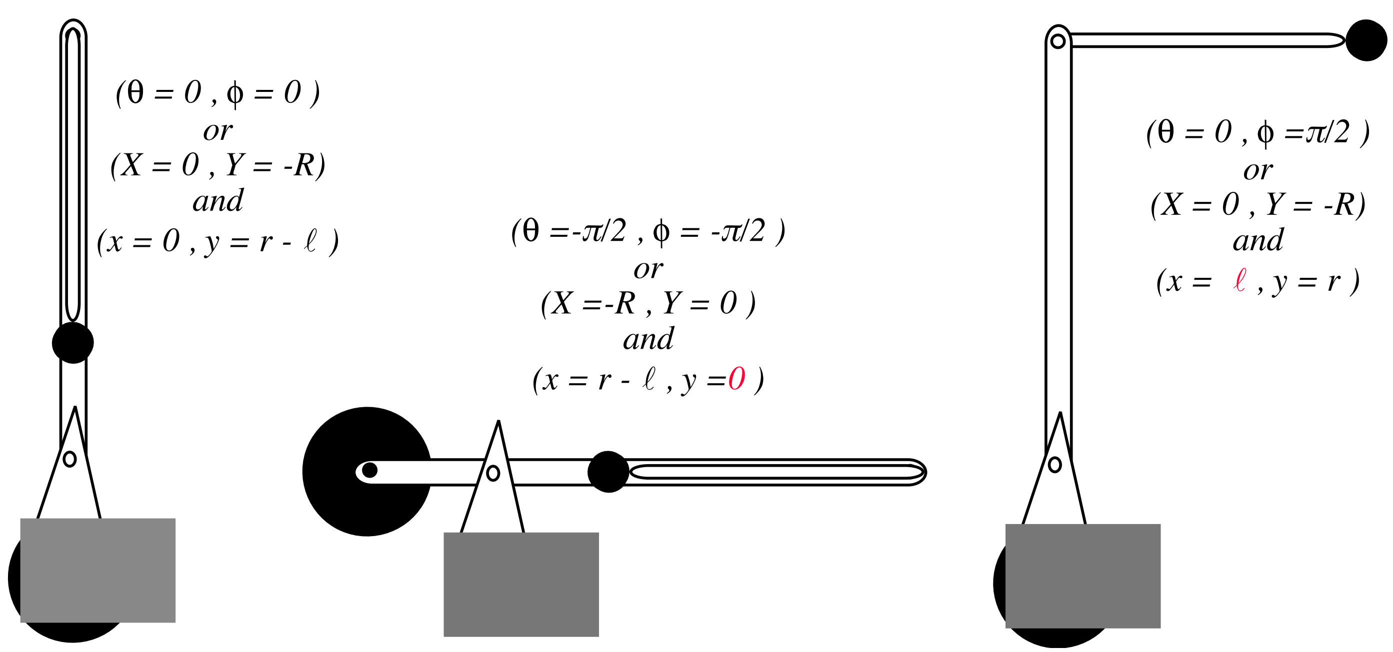

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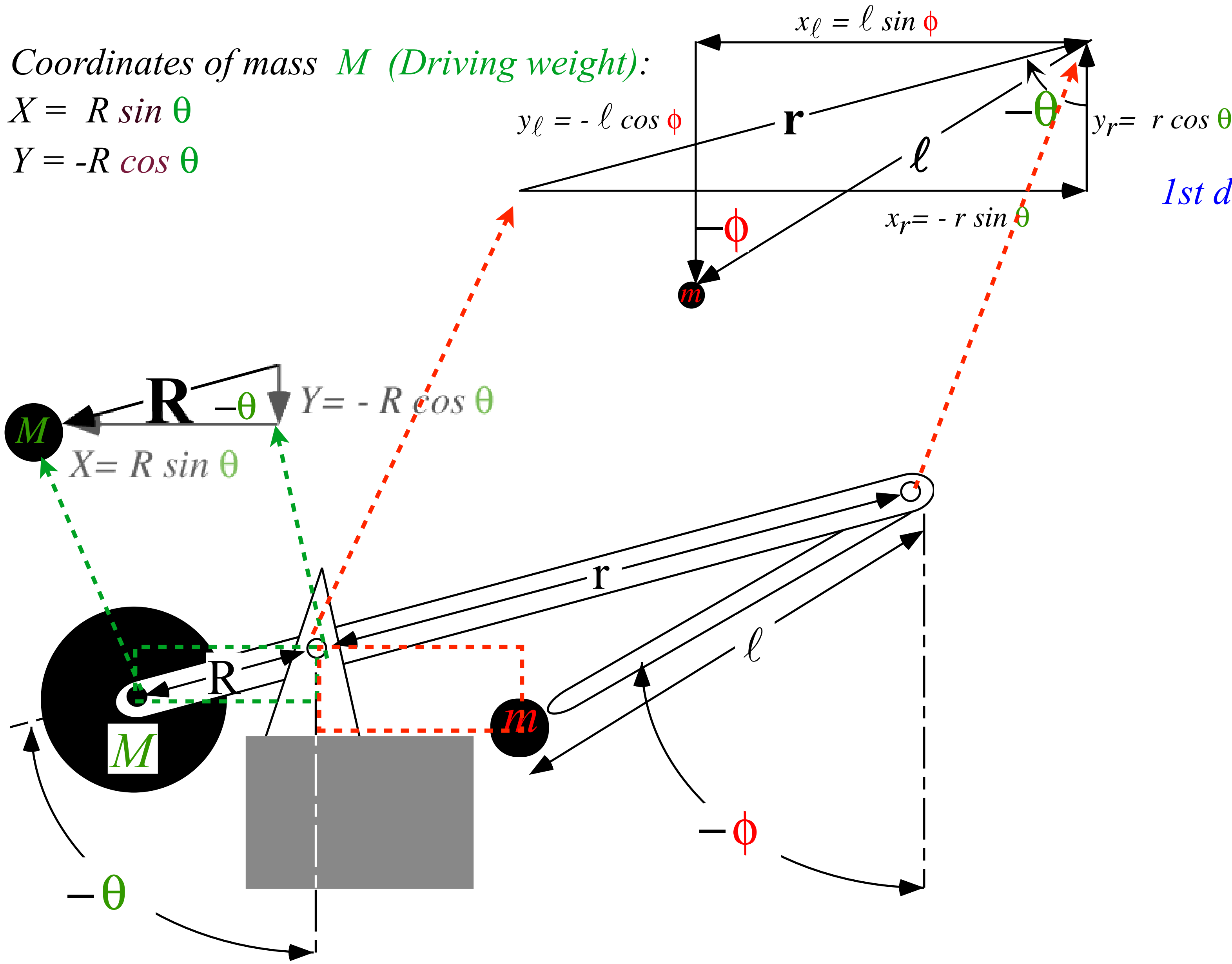

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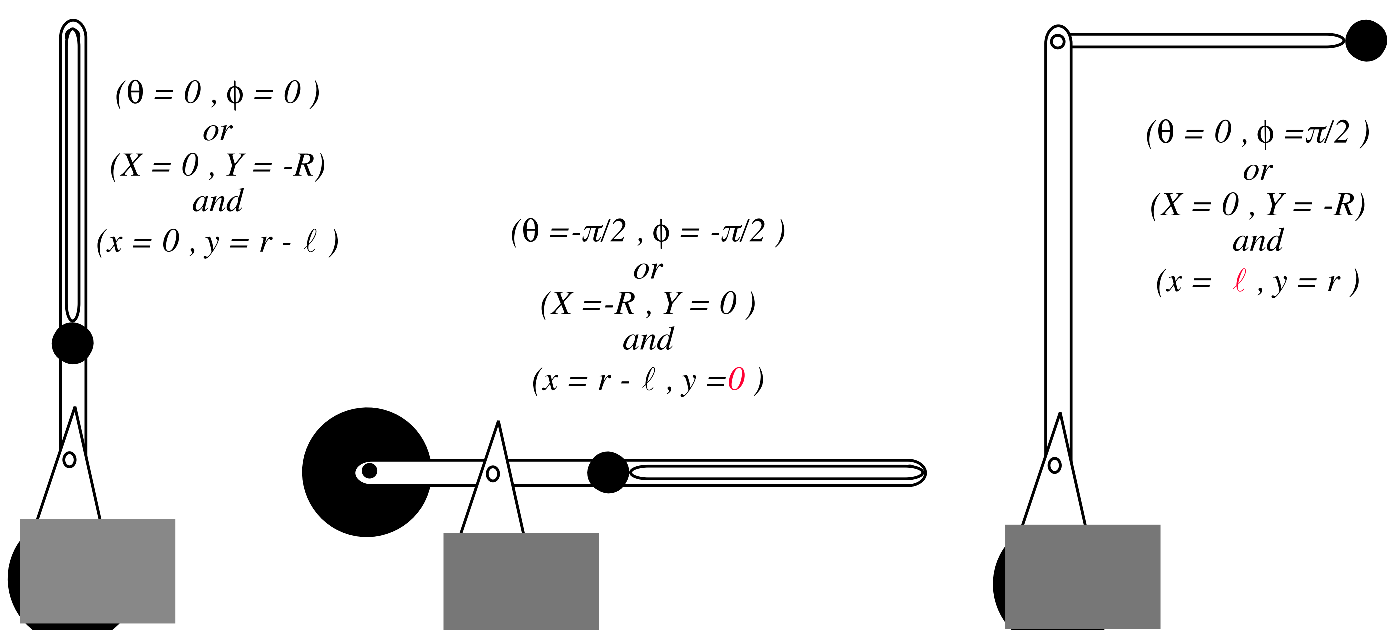

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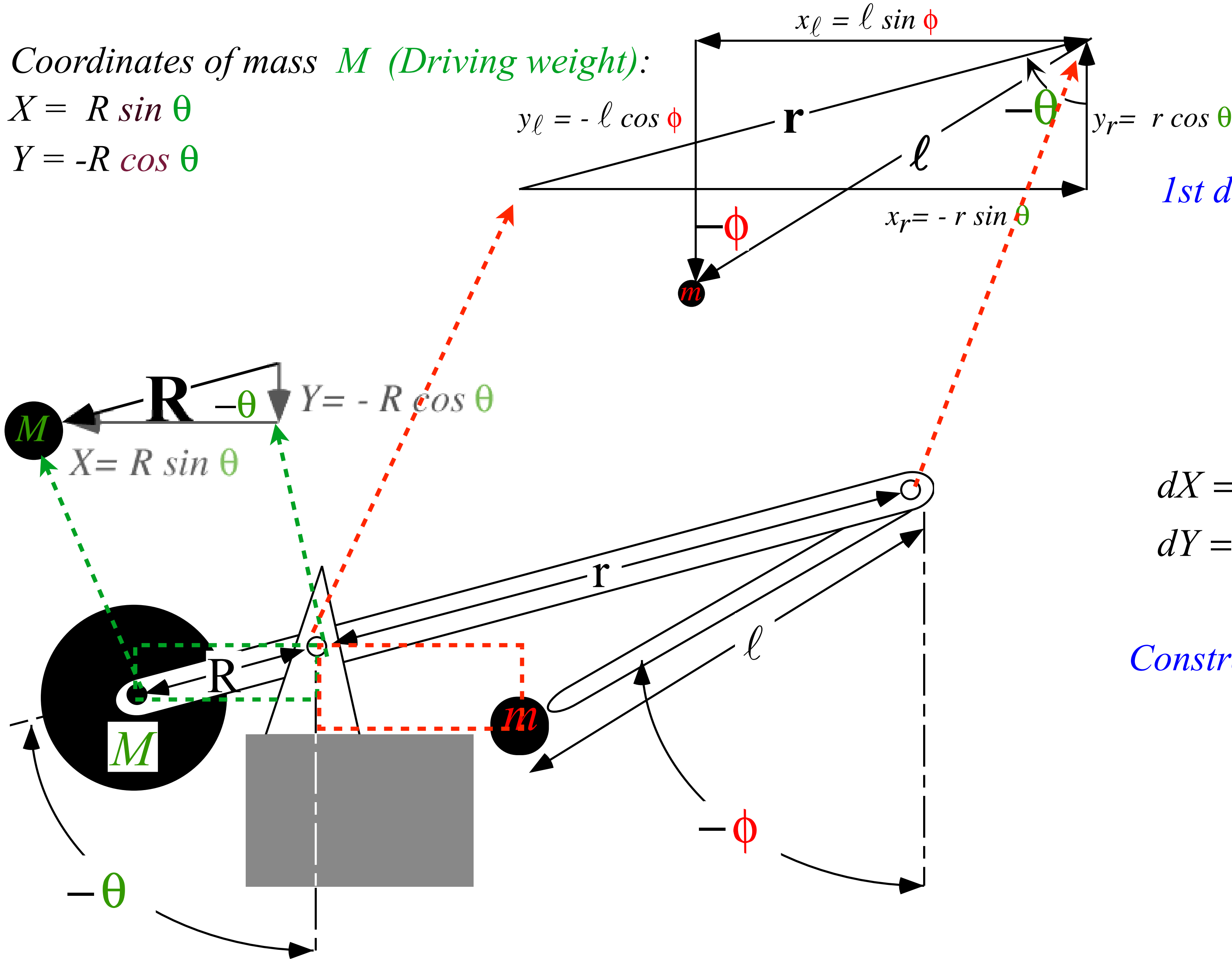

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$$dX = R\cos\theta\, d\theta + 0, \qquad dx = -r\cos\theta\, d\theta + \ell\cos\phi\, d\phi$$

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$c_R(X,Y) = X^2 + Y^2 = R^2 = const.$

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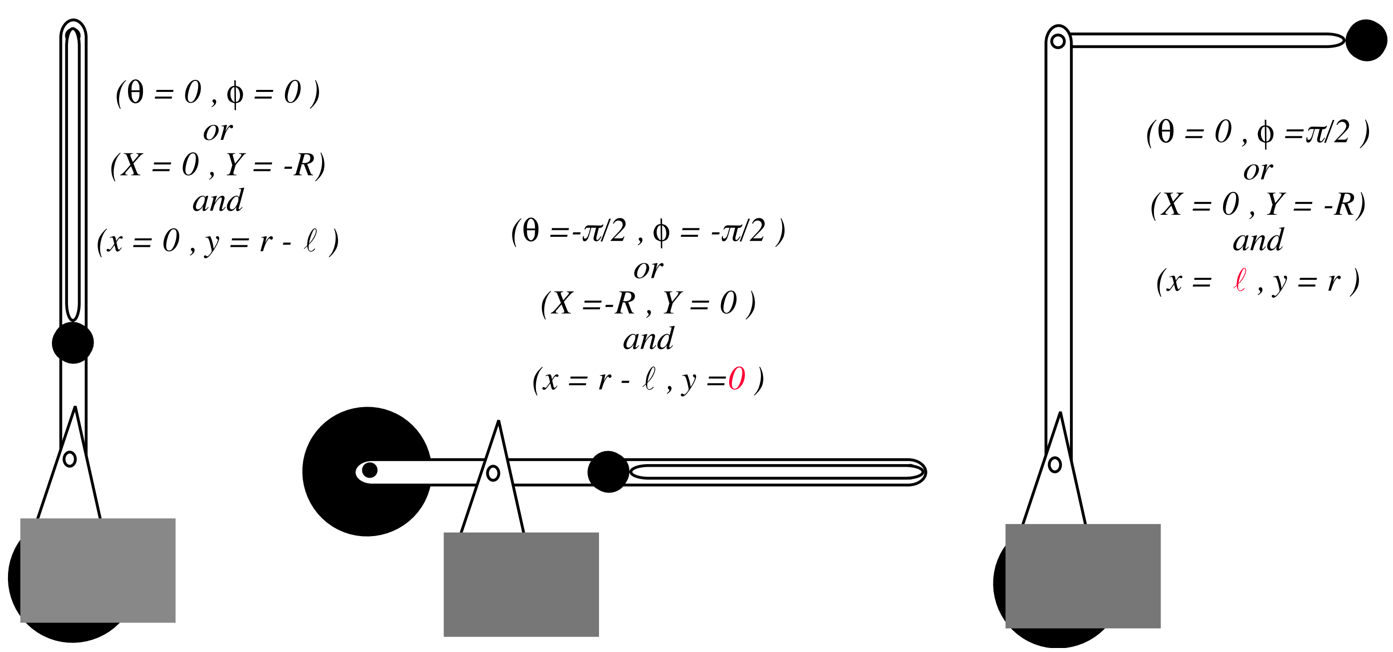

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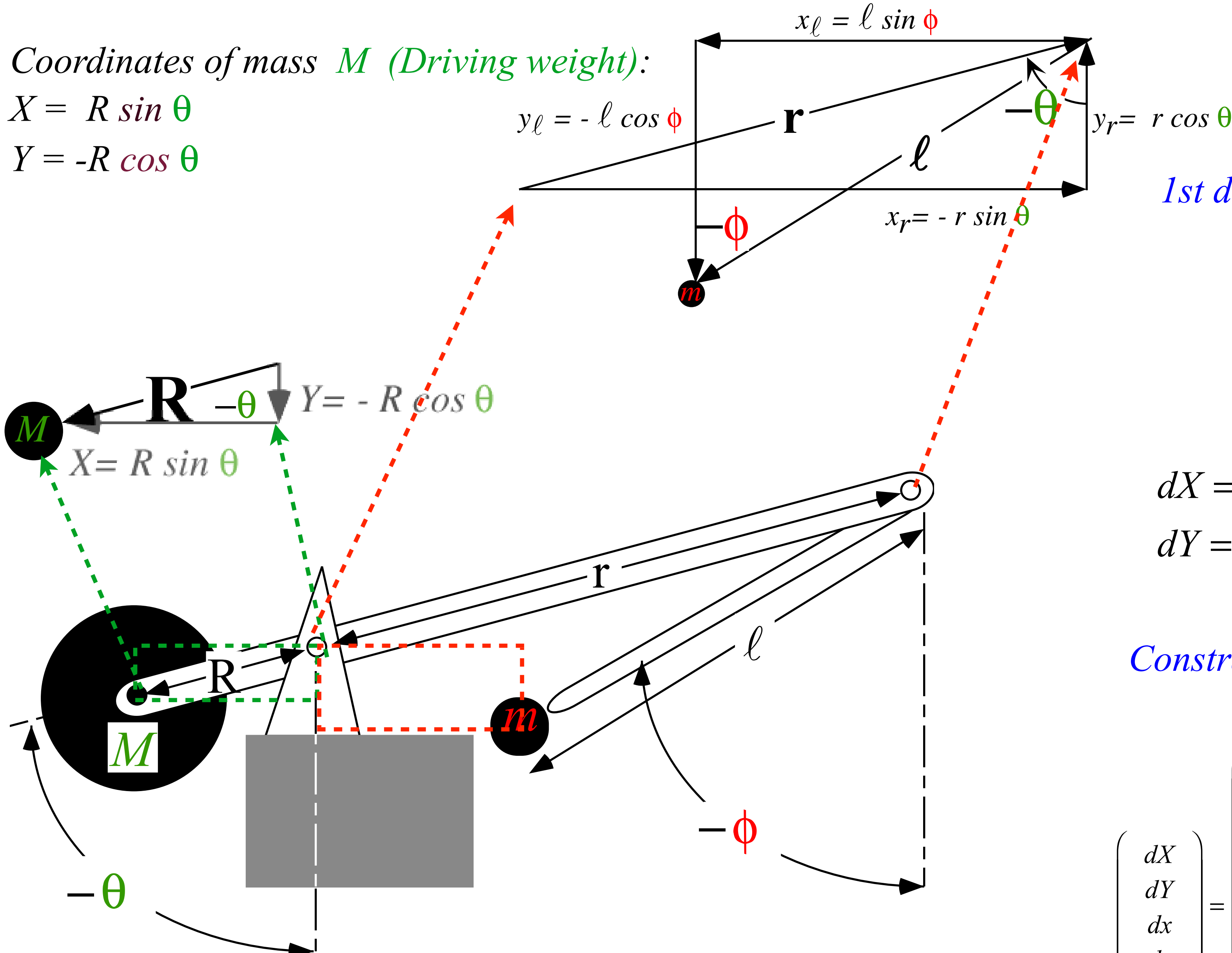

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Raw Jacobian form

$$\begin{pmatrix} dX \\ dY \\ dx \\ dy \end{pmatrix} = \begin{pmatrix} \frac{\partial X}{\partial\theta} & \frac{\partial X}{\partial\phi} \\ \frac{\partial Y}{\partial\theta} & \frac{\partial Y}{\partial\phi} \\ \frac{\partial x}{\partial\theta} & \frac{\partial x}{\partial\phi} \\ \frac{\partial y}{\partial\theta} & \frac{\partial y}{\partial\phi} \end{pmatrix} \begin{pmatrix} d\theta \\ d\phi \end{pmatrix} = \begin{pmatrix} R\cos\theta & 0 \\ R\sin\theta & 0 \\ -r\cos\theta & \ell\cos\phi \\ -r\sin\theta & \ell\sin\phi \end{pmatrix} \begin{pmatrix} d\theta \\ d\phi \end{pmatrix}$$

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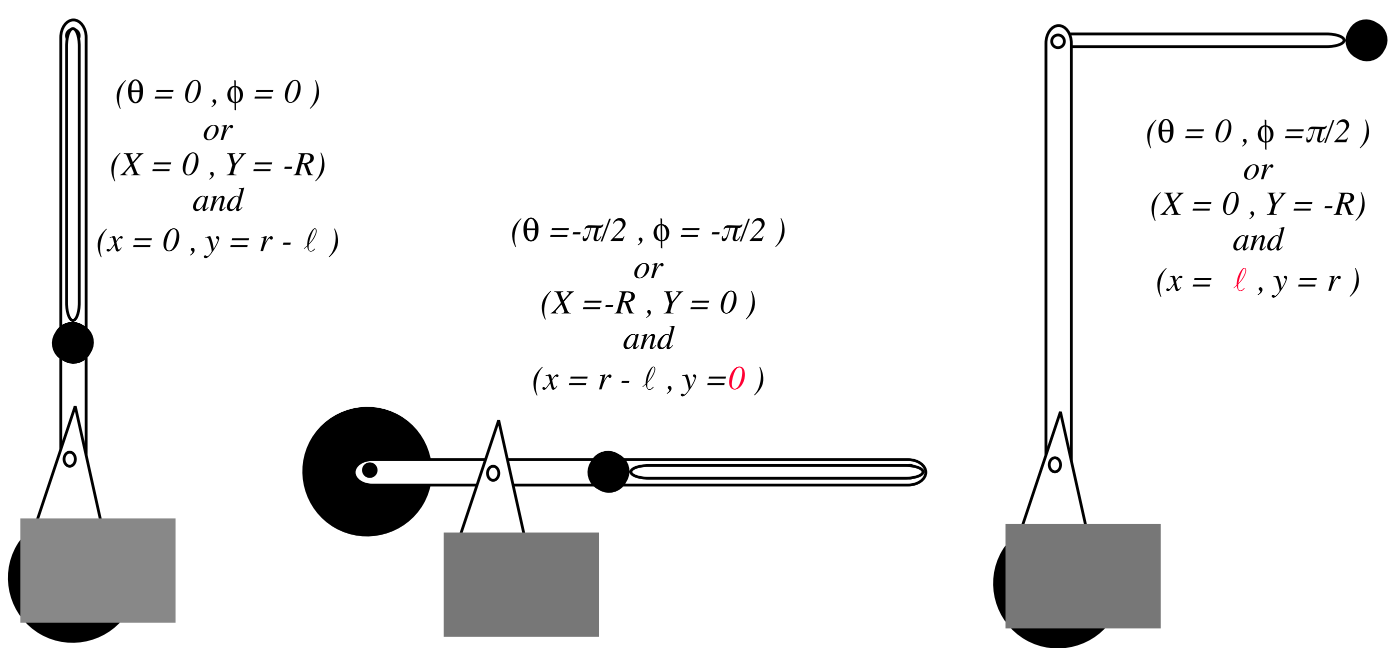

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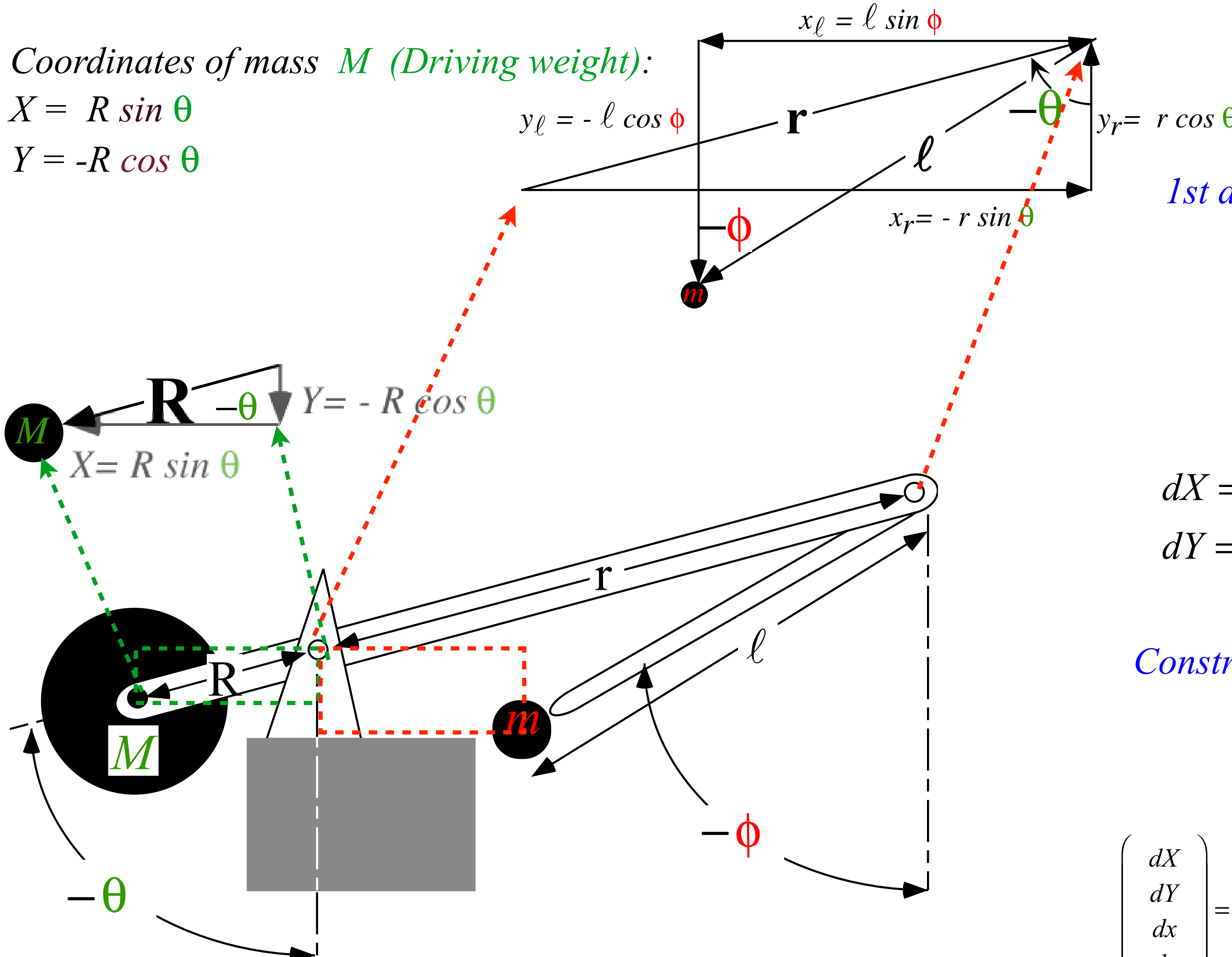

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Finding a reduced Jacobian form

$$\begin{pmatrix} dX \\ dY \end{pmatrix} = \begin{pmatrix} \frac{\partial X}{\partial\theta} & \frac{\partial X}{\partial\phi} \\ \frac{\partial Y}{\partial\theta} & \frac{\partial Y}{\partial\phi} \end{pmatrix} \begin{pmatrix} d\theta \\ d\phi \end{pmatrix} = \begin{pmatrix} R\cos\theta & 0 \\ R\sin\theta & 0 \end{pmatrix} \begin{pmatrix} d\theta \\ d\phi \end{pmatrix} \text{ FAILS since: } \det \begin{vmatrix} R\cos\theta & 0 \\ R\sin\theta & 0 \end{vmatrix} = 0$$

FAILS! (Always singular)

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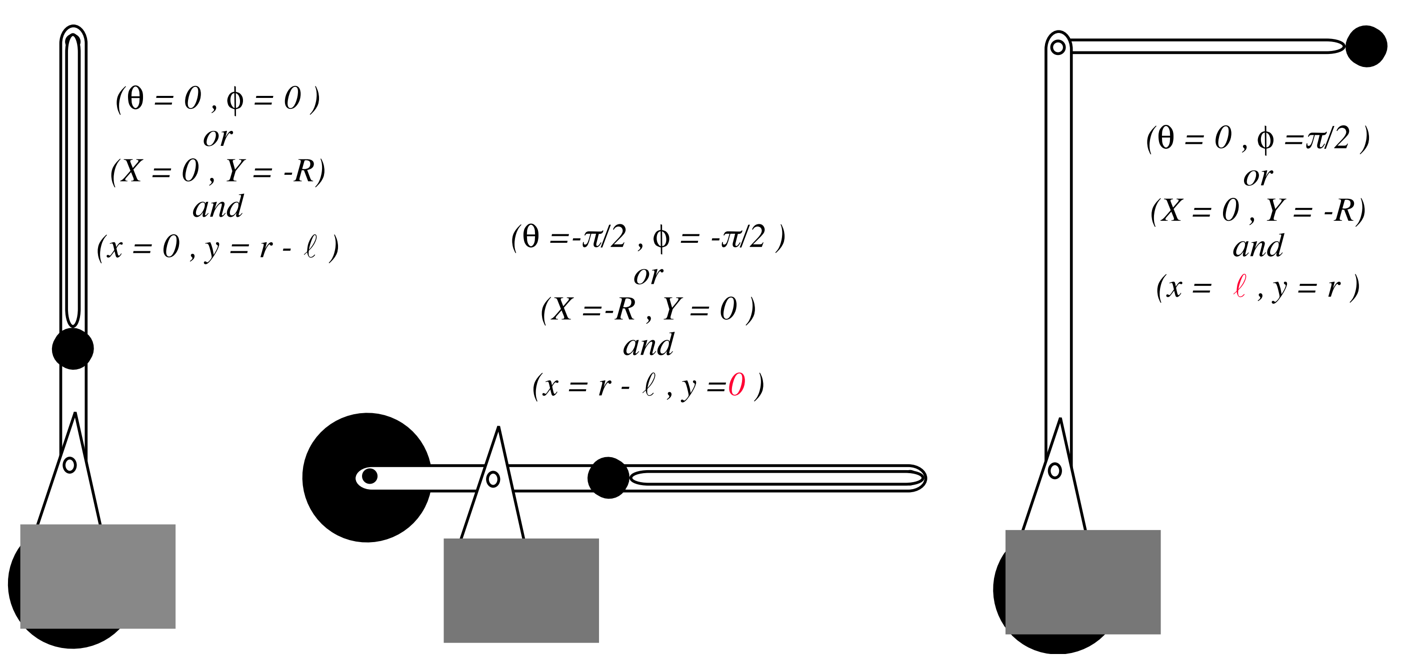
Fig. 2.2.2 Singular positions of the trebuchet



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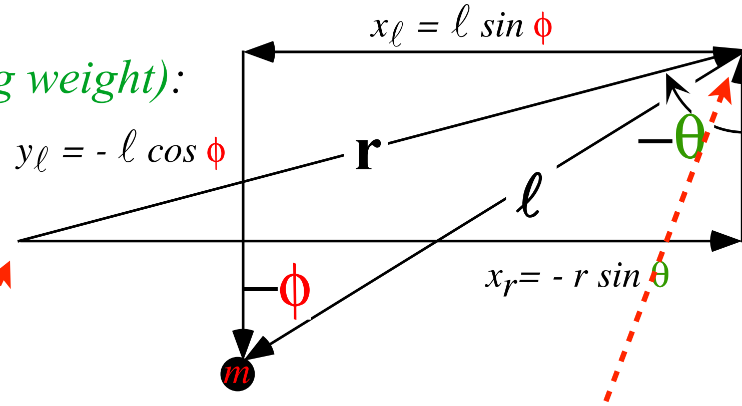

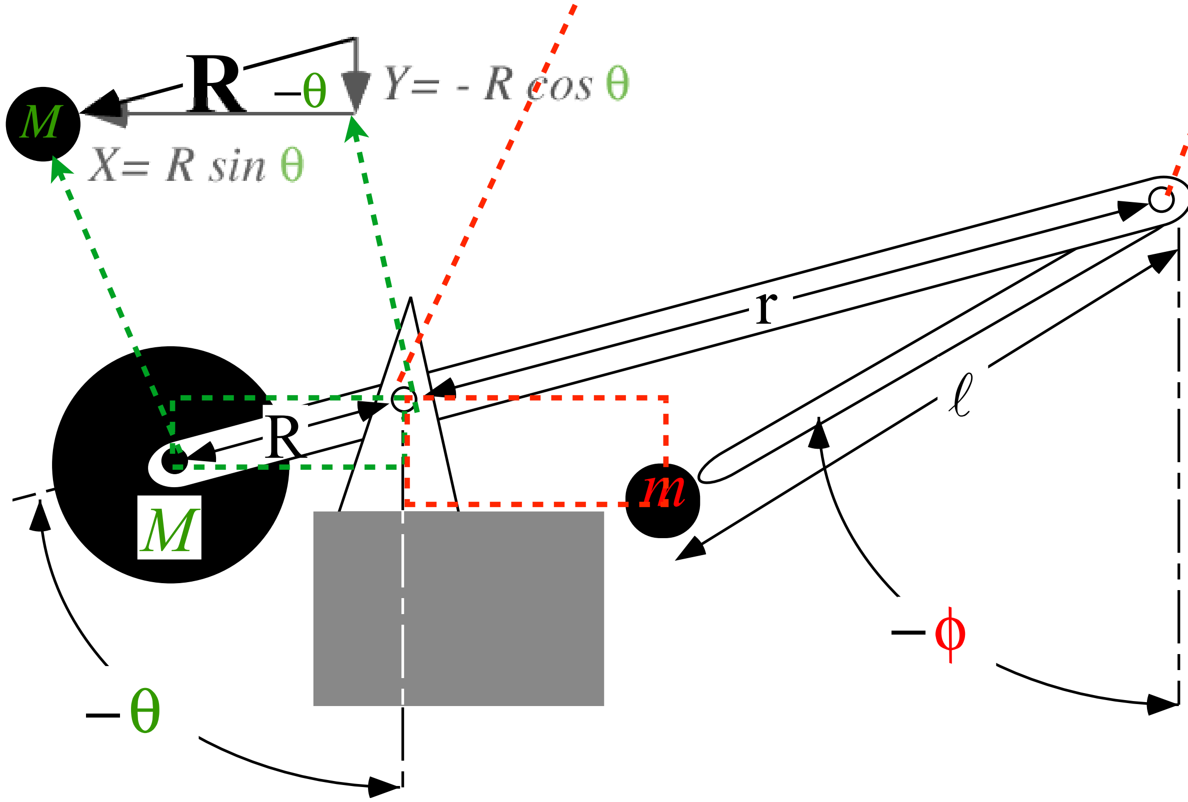

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Finding a reduced Jacobian form

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FAILS! (Always singular)

$$\begin{pmatrix} dx \\ dy \end{pmatrix} = \begin{pmatrix} \frac{\partial x}{\partial\theta} & \frac{\partial x}{\partial\phi} \\ \frac{\partial y}{\partial\theta} & \frac{\partial y}{\partial\phi} \end{pmatrix} \begin{pmatrix} d\theta \\ d\phi \end{pmatrix} = \begin{pmatrix} -r\cos\theta & \ell\cos\phi \\ -r\sin\theta & \ell\sin\phi \end{pmatrix} \begin{pmatrix} d\theta \\ d\phi \end{pmatrix}$$

OK: $\det\begin{vmatrix} -r\cos\theta & \ell\cos\phi \\ -r\sin\theta & \ell\sin\phi \end{vmatrix} = r\ell\sin(\theta-\phi)$

SUCCESS! (Usually non-singular)

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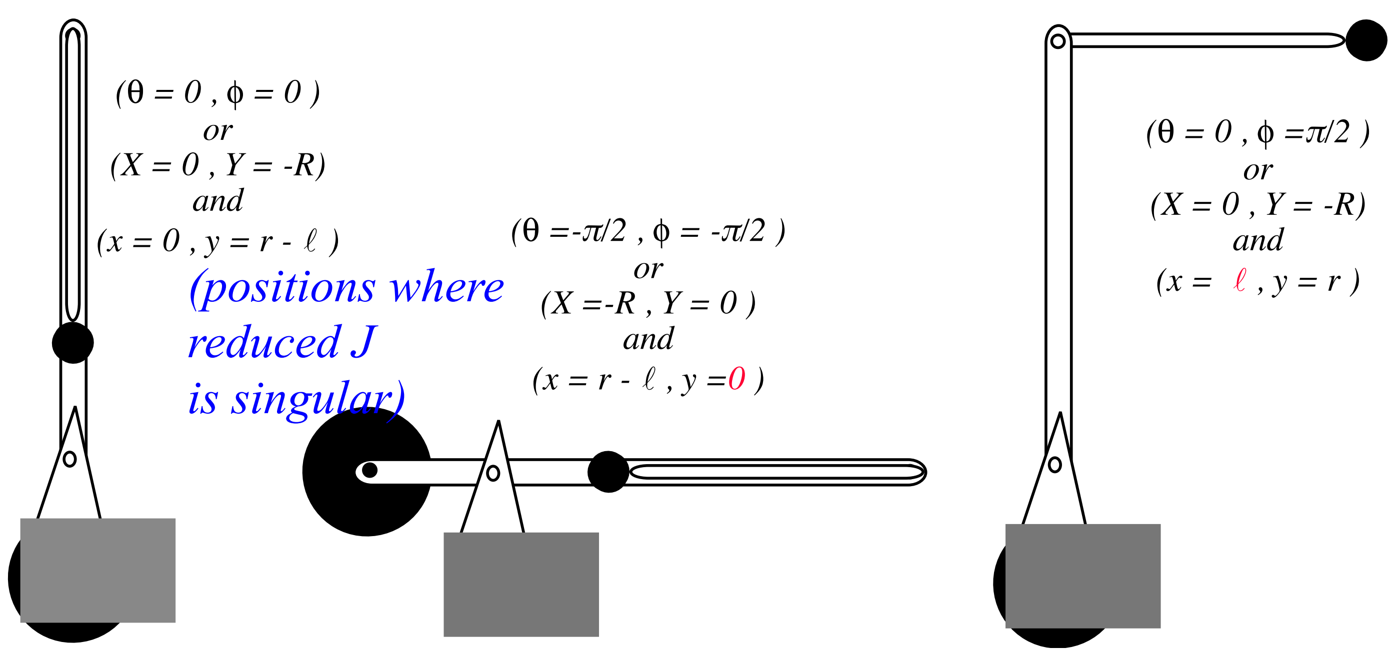
Fig. 2.2.2 Singular positions of the trebuchet



Cartesian to GCC transformations

Jacobian relations

→ *Kinetic energy calculation*

Dynamic metric tensor γ_{mn}

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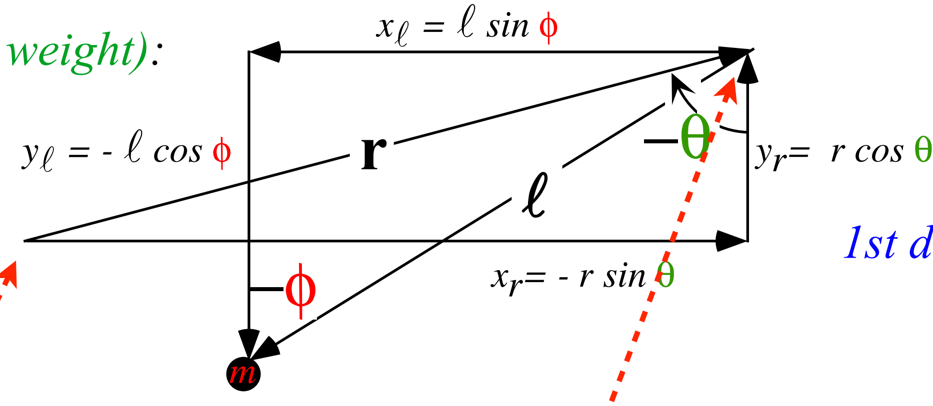

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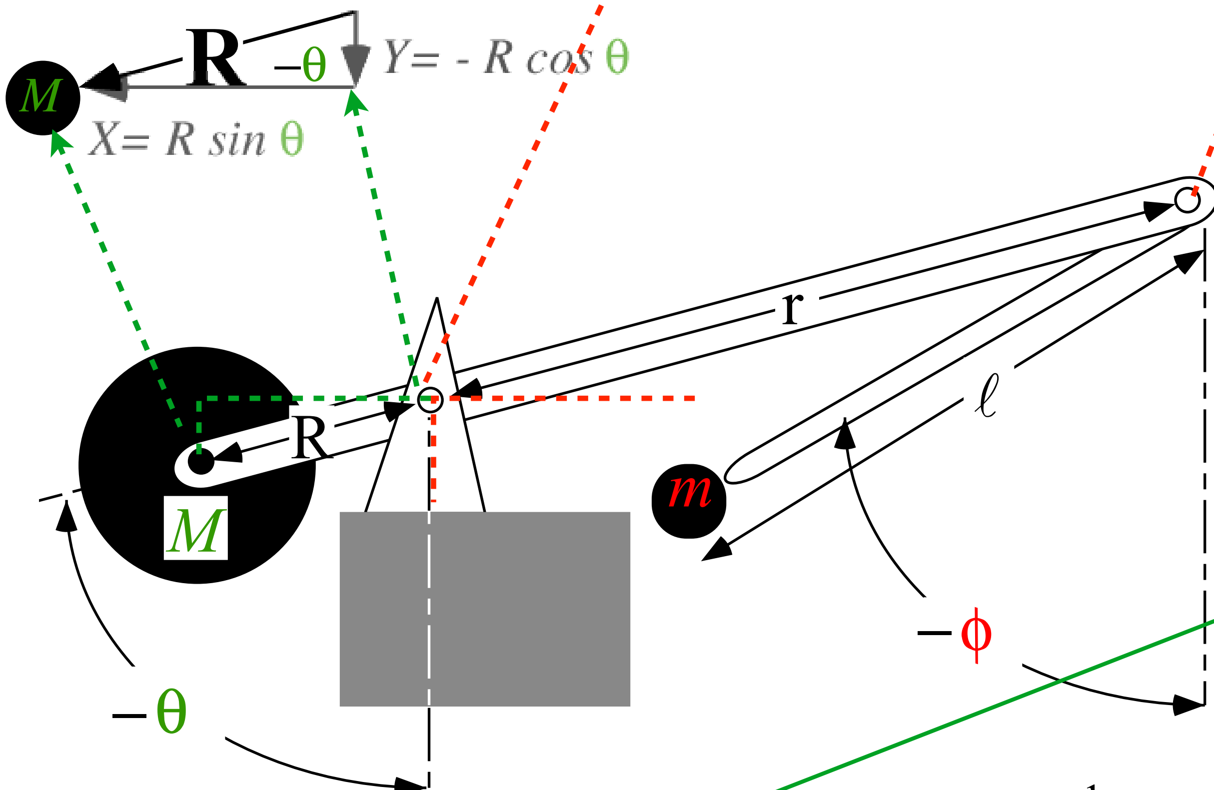
1st differential relations:

$$dX = \frac{\partial X}{\partial\theta}d\theta + \frac{\partial X}{\partial\phi}d\phi, \qquad dx = \frac{\partial x}{\partial\theta}d\theta + \frac{\partial x}{\partial\phi}d\phi,$$

$$dY = \frac{\partial Y}{\partial\theta}d\theta + \frac{\partial Y}{\partial\phi}d\phi, \qquad dy = \frac{\partial y}{\partial\theta}d\theta + \frac{\partial y}{\partial\phi}d\phi.$$

$$dX = R\cos\theta\, d\theta + 0, \qquad dx = -r\cos\theta\, d\theta + \ell\cos\phi\, d\phi$$

$$dY = R\sin\theta\, d\theta + 0, \qquad dy = -r\sin\theta\, d\theta + \ell\sin\phi\, d\phi$$



GCC Velocity relations:

$$\dot{X} = R\cos\theta\ \dot{\theta} + 0, \qquad \dot{x} = -r\cos\theta\ \dot{\theta} + \ell\cos\phi\ \dot{\phi}$$

$$\dot{Y} = R\sin\theta\ \dot{\theta} + 0, \qquad \dot{y} = -r\sin\theta\ \dot{\theta} + \ell\sin\phi\ \dot{\phi}$$

Kinetic energy of projectile m

$$T(m) = \frac{1}{2}m\begin{pmatrix}\dot{x} & \dot{y}\end{pmatrix}\begin{pmatrix}\dot{x}\\ \dot{y}\end{pmatrix} = \frac{1}{2}m\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}\frac{\partial x}{\partial\theta} & \frac{\partial x}{\partial\phi}\\ \frac{\partial y}{\partial\theta} & \frac{\partial y}{\partial\phi}\end{pmatrix}^T\begin{pmatrix}\frac{\partial x}{\partial\theta} & \frac{\partial x}{\partial\phi}\\ \frac{\partial y}{\partial\theta} & \frac{\partial y}{\partial\phi}\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}$$

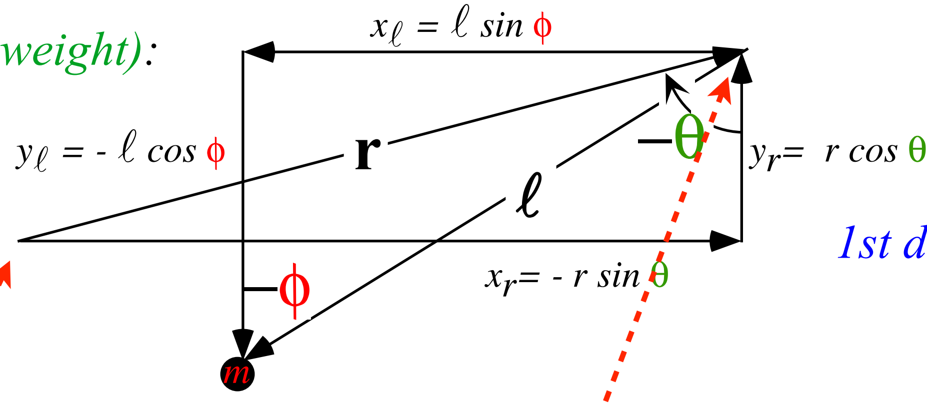
Kinetic energy of driver M

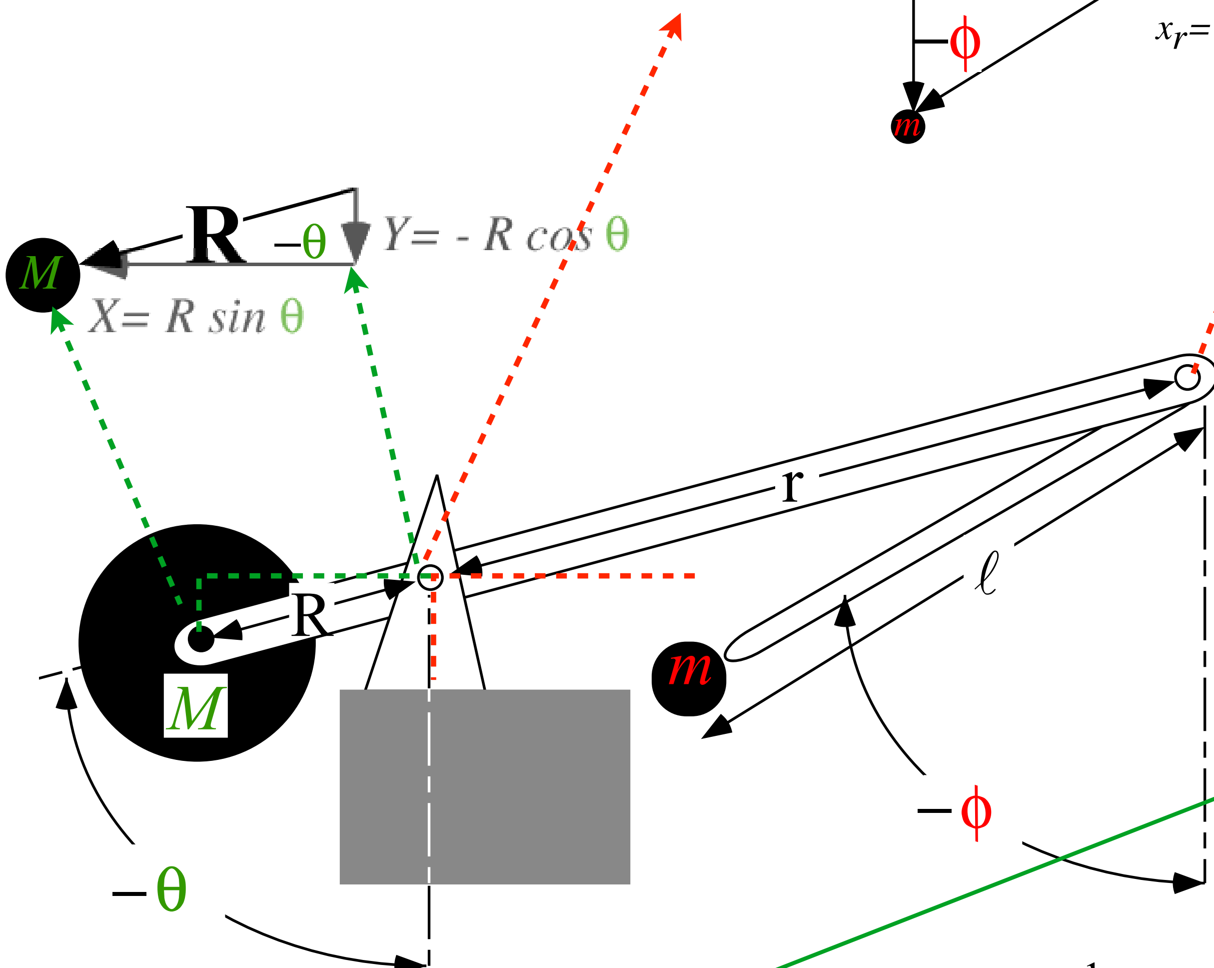
$$T(M) = \frac{1}{2}M\dot{X}^2 + \frac{1}{2}M\dot{Y}^2$$

Coordinates of mass M (Driving weight):

$X = R \sin \theta$

$Y = -R \cos \theta$





Coordinates of mass m (Payload or projectile):

$x = x_r + x_\ell = -r \sin \theta + \ell \sin \phi$

$y = y_r + y_\ell = r \cos \theta - \ell \cos \phi$

1st differential relations:

$$dX = \frac{\partial X}{\partial \theta} d\theta + \frac{\partial X}{\partial \phi} d\phi, \qquad dx = \frac{\partial x}{\partial \theta} d\theta + \frac{\partial x}{\partial \phi} d\phi,$$

$$dY = \frac{\partial Y}{\partial \theta} d\theta + \frac{\partial Y}{\partial \phi} d\phi, \qquad dy = \frac{\partial y}{\partial \theta} d\theta + \frac{\partial y}{\partial \phi} d\phi.$$

$$dX = R\cos\theta \; d\theta + 0, \qquad dx = -r\cos\theta \; d\theta + \ell\cos\phi \; d\phi$$

$$dY = R\sin\theta \; d\theta + 0, \qquad dy = -r\sin\theta \; d\theta + \ell\sin\phi \; d\phi$$

GCC Velocity relations:

$$\dot{X} = R\cos\theta \;\; \dot{\theta} + 0, \qquad \dot{x} = -r\cos\theta \;\; \dot{\theta} + \ell\cos\phi \;\; \dot{\phi}$$

$$\dot{Y} = R\sin\theta \;\; \dot{\theta} + 0, \qquad \dot{y} = -r\sin\theta \;\; \dot{\theta} + \ell\sin\phi \;\; \dot{\phi}$$

Kinetic energy of projectile m

$$T(m) = \frac{1}{2} m \begin{pmatrix} \dot{x} & \dot{y} \end{pmatrix} \begin{pmatrix} \dot{x} \\ \dot{y} \end{pmatrix} = \frac{1}{2} m \begin{pmatrix} \dot{\theta} & \dot{\phi} \end{pmatrix} \begin{pmatrix} \frac{\partial x}{\partial \theta} & \frac{\partial x}{\partial \phi} \\ \frac{\partial y}{\partial \theta} & \frac{\partial y}{\partial \phi} \end{pmatrix}^T \begin{pmatrix} \frac{\partial x}{\partial \theta} & \frac{\partial x}{\partial \phi} \\ \frac{\partial y}{\partial \theta} & \frac{\partial y}{\partial \phi} \end{pmatrix} \begin{pmatrix} \dot{\theta} \\ \dot{\phi} \end{pmatrix}$$

$$= \frac{1}{2} m \begin{pmatrix} \dot{\theta} & \dot{\phi} \end{pmatrix} \begin{pmatrix} -r\cos\theta & -r\sin\theta \\ \ell\cos\phi & \ell\sin\phi \end{pmatrix} \begin{pmatrix} -r\cos\theta & \ell\cos\phi \\ -r\sin\theta & \ell\sin\phi \end{pmatrix} \begin{pmatrix} \dot{\theta} \\ \dot{\phi} \end{pmatrix}$$

Kinetic energy of driver M

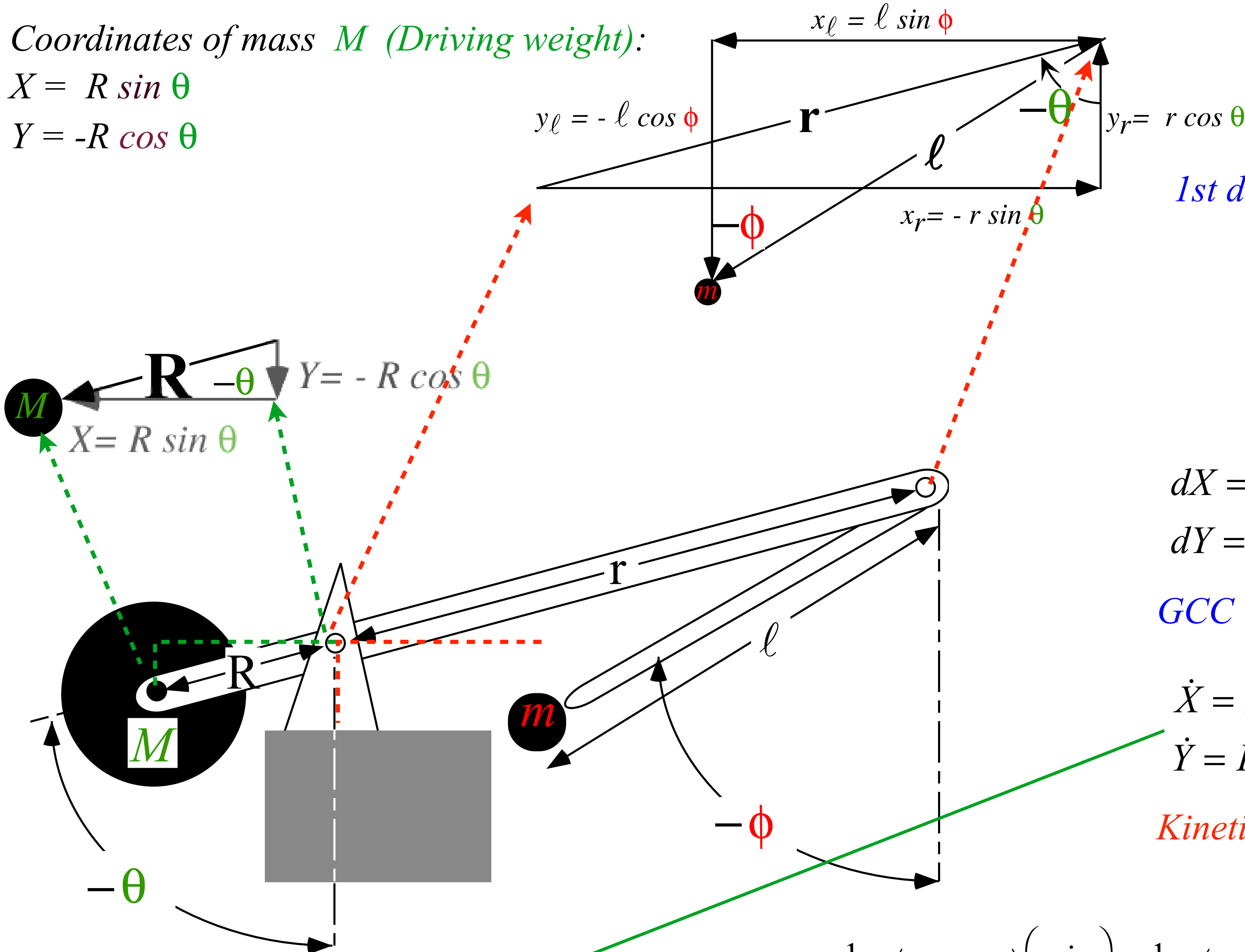
$$T(M) = \frac{1}{2} M \dot{X}^2 + \frac{1}{2} M \dot{Y}^2$$

$$= \frac{1}{2} M \left(R\cos\theta \;\; \dot{\theta}\right)^2 + \frac{1}{2} M \left(R\sin\theta \;\; \dot{\theta}\right)^2$$

Coordinates of mass M (Driving weight):

$X = R \sin\theta$

$Y = -R\cos\theta$



Coordinates of mass m (Payload or projectile):

$x = x_r + x_\ell = - r\sin\theta + \ell\sin\phi$

$y = y_r + y_\ell = r\cos\theta - \ell\cos\phi$

1st differential relations:

$$dX = \frac{\partial X}{\partial\theta}d\theta + \frac{\partial X}{\partial\phi}d\phi, \qquad dx = \frac{\partial x}{\partial\theta}d\theta + \frac{\partial x}{\partial\phi}d\phi,$$

$$dY = \frac{\partial Y}{\partial\theta}d\theta + \frac{\partial Y}{\partial\phi}d\phi, \qquad dy = \frac{\partial y}{\partial\theta}d\theta + \frac{\partial y}{\partial\phi}d\phi.$$

$$dX = R\cos\theta\, d\theta + 0, \qquad dx = -r\cos\theta\, d\theta + \ell\cos\phi\, d\phi$$

$$dY = R\sin\theta\, d\theta + 0, \qquad dy = -r\sin\theta\, d\theta + \ell\sin\phi\, d\phi$$

GCC Velocity relations:

$$\dot{X} = R\cos\theta\ \dot{\theta} + 0, \qquad \dot{x} = -r\cos\theta\ \dot{\theta} + \ell\cos\phi\ \dot{\phi}$$

$$\dot{Y} = R\sin\theta\ \dot{\theta} + 0, \qquad \dot{y} = -r\sin\theta\ \dot{\theta} + \ell\sin\phi\ \dot{\phi}$$

Kinetic energy of projectile m

$$T(m) = \frac{1}{2}m\begin{pmatrix}\dot{x} & \dot{y}\end{pmatrix}\begin{pmatrix}\dot{x}\\ \dot{y}\end{pmatrix} = \frac{1}{2}m\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}\frac{\partial x}{\partial\theta} & \frac{\partial x}{\partial\phi}\\ \frac{\partial y}{\partial\theta} & \frac{\partial y}{\partial\phi}\end{pmatrix}^T\begin{pmatrix}\frac{\partial x}{\partial\theta} & \frac{\partial x}{\partial\phi}\\ \frac{\partial y}{\partial\theta} & \frac{\partial y}{\partial\phi}\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}$$

$$= \frac{1}{2}m\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}-r\cos\theta & -r\sin\theta\\ \ell\cos\phi & \ell\sin\phi\end{pmatrix}\begin{pmatrix}-r\cos\theta & \ell\cos\phi\\ -r\sin\theta & \ell\sin\phi\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}$$

$$= \frac{1}{2}m\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}r^2\cos^2\theta + r^2\sin^2\theta & -r\ell\cos\theta\cos\phi - r\ell\sin\theta\sin\phi\\ -\ell r\cos\phi\cos\theta - r\ell\sin\theta\sin\phi & \ell^2\cos^2\phi + \ell^2\sin^2\phi\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}$$

Kinetic energy of driver M

$$T(M) = \frac{1}{2}M\dot{X}^2 + \frac{1}{2}M\dot{Y}^2$$

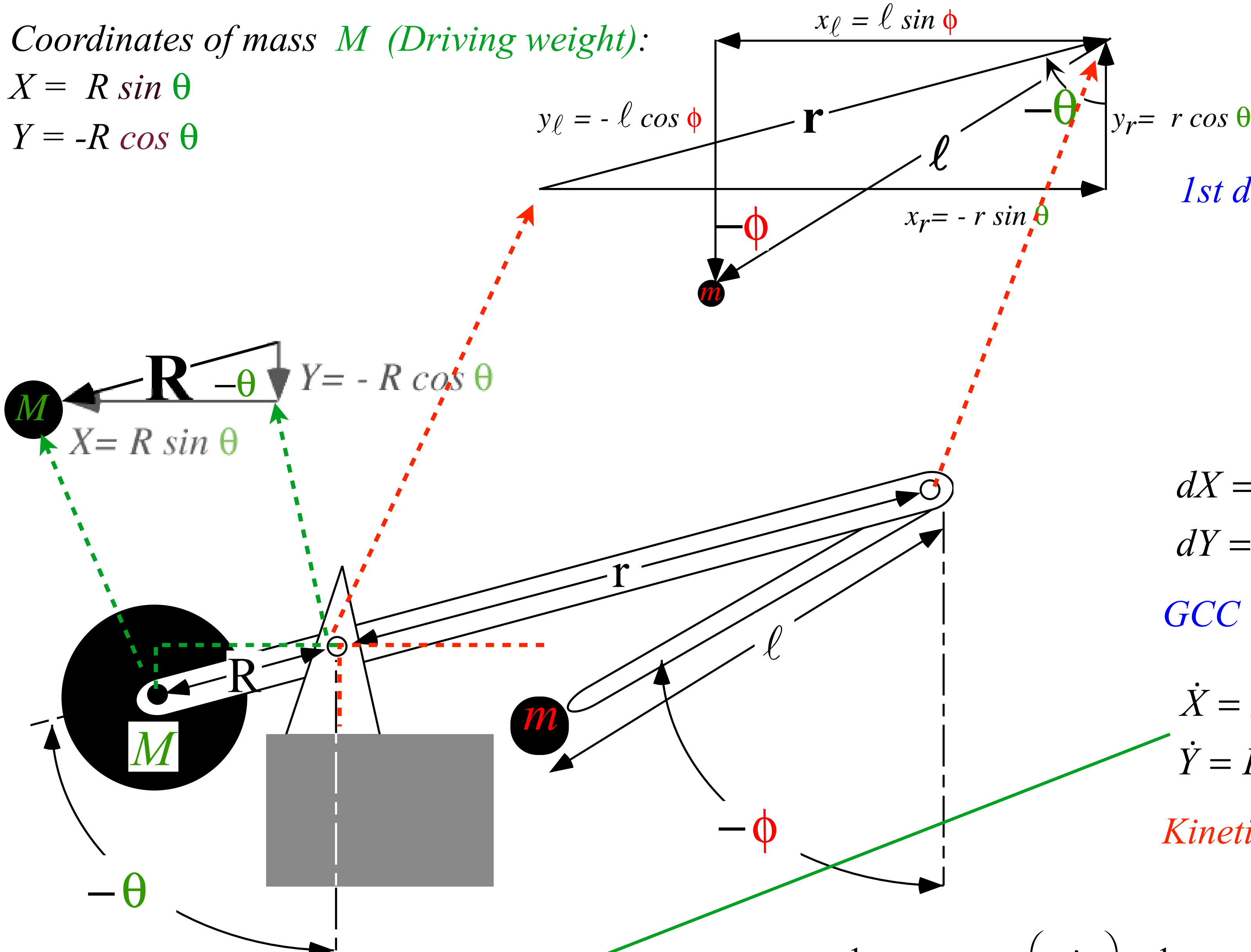
$$= \frac{1}{2}M\left(R\cos\theta\ \dot{\theta}\right)^2 + \frac{1}{2}M\left(R\sin\theta\ \dot{\theta}\right)^2$$

$$= \frac{1}{2}MR^2\dot{\theta}^2$$

Coordinates of mass M (Driving weight):

$X = R \sin\theta$

$Y = -R\cos\theta$



Coordinates of mass m (Payload or projectile):

$x = x_r + x_\ell = -r\sin\theta + \ell\sin\phi$

$y = y_r + y_\ell = r\cos\theta - \ell\cos\phi$

1st differential relations:

$$dX = \frac{\partial X}{\partial\theta}d\theta + \frac{\partial X}{\partial\phi}d\phi, \qquad dx = \frac{\partial x}{\partial\theta}d\theta + \frac{\partial x}{\partial\phi}d\phi,$$

$$dY = \frac{\partial Y}{\partial\theta}d\theta + \frac{\partial Y}{\partial\phi}d\phi, \qquad dy = \frac{\partial y}{\partial\theta}d\theta + \frac{\partial y}{\partial\phi}d\phi.$$

$$dX = R\cos\theta\, d\theta + 0, \qquad dx = -r\cos\theta\, d\theta + \ell\cos\phi\, d\phi$$

$$dY = R\sin\theta\, d\theta + 0, \qquad dy = -r\sin\theta\, d\theta + \ell\sin\phi\, d\phi$$

GCC Velocity relations:

$$\dot{X} = R\cos\theta\ \dot\theta + 0, \qquad \dot{x} = -r\cos\theta\ \dot\theta + \ell\cos\phi\ \dot\phi$$

$$\dot{Y} = R\sin\theta\ \dot\theta + 0, \qquad \dot{y} = -r\sin\theta\ \dot\theta + \ell\sin\phi\ \dot\phi$$

Kinetic energy of projectile m

$$T(m) = \frac{1}{2}m\begin{pmatrix}\dot x & \dot y\end{pmatrix}\begin{pmatrix}\dot x\\ \dot y\end{pmatrix} = \frac{1}{2}m\begin{pmatrix}\dot\theta & \dot\phi\end{pmatrix}\begin{pmatrix}\frac{\partial x}{\partial\theta} & \frac{\partial x}{\partial\phi}\\ \frac{\partial y}{\partial\theta} & \frac{\partial y}{\partial\phi}\end{pmatrix}^T\begin{pmatrix}\frac{\partial x}{\partial\theta} & \frac{\partial x}{\partial\phi}\\ \frac{\partial y}{\partial\theta} & \frac{\partial y}{\partial\phi}\end{pmatrix}\begin{pmatrix}\dot\theta\\ \dot\phi\end{pmatrix}$$

$$= \frac{1}{2}m\begin{pmatrix}\dot\theta & \dot\phi\end{pmatrix}\begin{pmatrix}-r\cos\theta & -r\sin\theta\\ \ell\cos\phi & \ell\sin\phi\end{pmatrix}\begin{pmatrix}-r\cos\theta & \ell\cos\phi\\ -r\sin\theta & \ell\sin\phi\end{pmatrix}\begin{pmatrix}\dot\theta\\ \dot\phi\end{pmatrix}$$

$$= \frac{1}{2}m\begin{pmatrix}\dot\theta & \dot\phi\end{pmatrix}\begin{pmatrix}r^2\cos^2\theta + r^2\sin^2\theta & -r\ell\cos\theta\cos\phi - r\ell\sin\theta\sin\phi\\ -\ell r\cos\phi\cos\theta - r\ell\sin\theta\sin\phi & \ell^2\cos^2\phi + \ell^2\sin^2\phi\end{pmatrix}\begin{pmatrix}\dot\theta\\ \dot\phi\end{pmatrix}$$

Kinetic energy of driver M

$$T(M) = \frac{1}{2}M\dot{X}^2 + \frac{1}{2}M\dot{Y}^2$$

$$= \frac{1}{2}M\left(R\cos\theta\ \dot\theta\right)^2 + \frac{1}{2}M\left(R\sin\theta\ \dot\theta\right)^2$$

$$= \frac{1}{2}MR^2\dot\theta^2$$

Total kinetic energy of M and m

$$\text{Total KE} = T = T(M) + T(m) = \frac{1}{2}\begin{pmatrix}\dot\theta & \dot\phi\end{pmatrix}\begin{pmatrix}MR^2 + mr^2 & -mr\ell\cos(\theta-\phi)\\ -mr\ell\cos(\theta-\phi) & m\ell^2\end{pmatrix}\begin{pmatrix}\dot\theta\\ \dot\phi\end{pmatrix} = \frac{1}{2}\left[(MR^2 + mr^2)\dot\theta^2 - 2mr\ell\cos(\theta-\phi)\,\dot\theta\dot\phi + m\ell^2\dot\phi^2\right]$$

Cartesian to GCC transformations

Jacobian relations

Kinetic energy calculation

→ *Dynamic metric tensor* γ_{mn}

Kinetic energy of driver M

$$T(M)=\frac{1}{2}M\dot{X}^2+\frac{1}{2}M\dot{Y}^2$$

$$=\frac{1}{2}MR^2\dot{\theta}^2$$

Kinetic energy of projectile m

$$T(m)=\frac{1}{2}m\begin{pmatrix}\dot{x} & \dot{y}\end{pmatrix}\begin{pmatrix}\dot{x}\\ \dot{y}\end{pmatrix}=\frac{1}{2}m\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}\frac{\partial x}{\partial\theta} & \frac{\partial x}{\partial\phi}\\ \frac{\partial y}{\partial\theta} & \frac{\partial y}{\partial\phi}\end{pmatrix}^T\begin{pmatrix}\frac{\partial x}{\partial\theta} & \frac{\partial x}{\partial\phi}\\ \frac{\partial y}{\partial\theta} & \frac{\partial y}{\partial\phi}\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}$$

$$=\frac{1}{2}m\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}-r\cos\theta & -r\sin\theta\\ \ell\cos\phi & \ell\sin\phi\end{pmatrix}\begin{pmatrix}-r\cos\theta & \ell\cos\phi\\ -r\sin\theta & \ell\sin\phi\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}$$

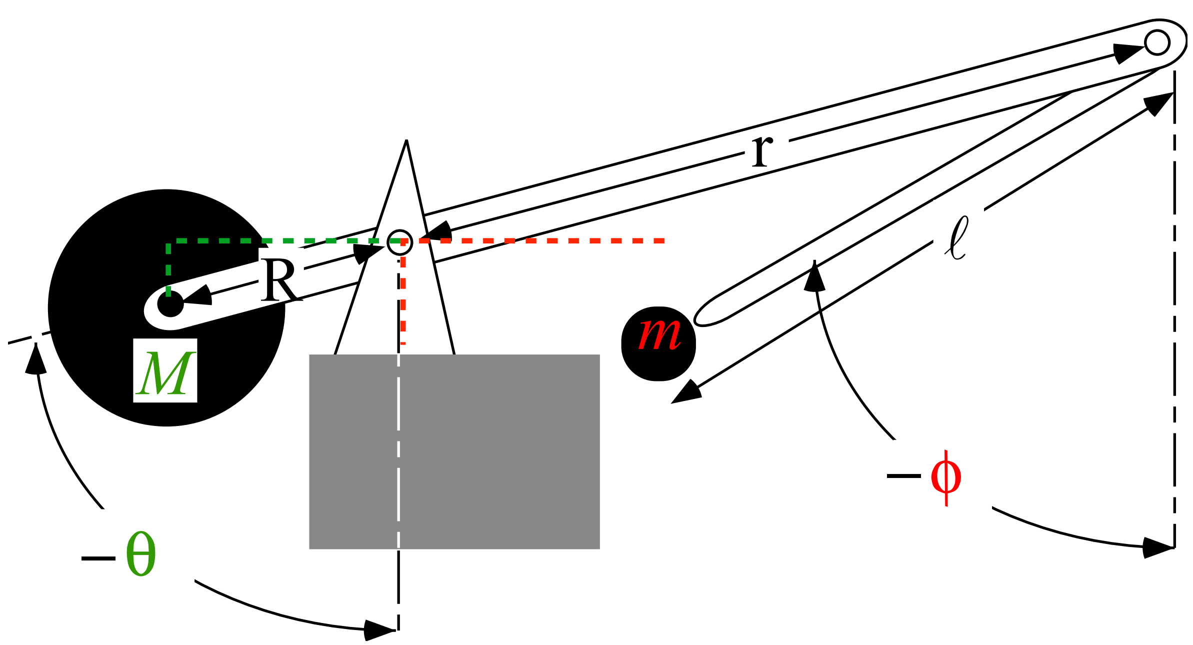
$$=\frac{1}{2}m\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}r^2\cos^2\theta+r^2\sin^2\theta & -r\ell\cos\theta\cos\phi-r\ell\sin\theta\sin\phi\\ -\ell r\cos\phi\cos\theta-r\ell\sin\theta\sin\phi & \ell^2\cos^2\phi+\ell^2\sin^2\phi\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}$$

Total kinetic energy of M and m

$$\text{Total } KE=T=T(M)+T(m)=\frac{1}{2}\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}MR^2+mr^2 & -mr\ell\cos(\theta-\phi)\\ -mr\ell\cos(\theta-\phi) & m\ell^2\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}=\frac{1}{2}\left[(MR^2+mr^2)\dot{\theta}^2-2mr\ell\cos(\theta-\phi)\,\dot{\theta}\dot{\phi}+m\ell^2\dot{\phi}^2\right]$$

Dynamic metric tensor γ_{mn}

$$\begin{pmatrix}\gamma_{\theta,\theta} & \gamma_{\theta,\phi}\\ \gamma_{\phi,\theta} & \gamma_{\phi,\phi}\end{pmatrix}$$



Kinetic energy of driver M

$$T(M)=\frac{1}{2}M\dot{X}^2+\frac{1}{2}M\dot{Y}^2$$

$$=\frac{1}{2}MR^2\dot{\theta}^2$$

Kinetic energy of projectile m

$$T(m)=\frac{1}{2}m\begin{pmatrix}\dot{x} & \dot{y}\end{pmatrix}\begin{pmatrix}\dot{x}\\ \dot{y}\end{pmatrix}=\frac{1}{2}m\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}\frac{\partial x}{\partial\theta} & \frac{\partial x}{\partial\phi}\\ \frac{\partial y}{\partial\theta} & \frac{\partial y}{\partial\phi}\end{pmatrix}^T\begin{pmatrix}\frac{\partial x}{\partial\theta} & \frac{\partial x}{\partial\phi}\\ \frac{\partial y}{\partial\theta} & \frac{\partial y}{\partial\phi}\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}$$

$$=\frac{1}{2}m\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}-r\cos\theta & -r\sin\theta\\ \ell\cos\phi & \ell\sin\phi\end{pmatrix}\begin{pmatrix}-r\cos\theta & \ell\cos\phi\\ -r\sin\theta & \ell\sin\phi\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}$$

$$=\frac{1}{2}m\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}r^2\cos^2\theta+r^2\sin^2\theta & -r\ell\cos\theta\cos\phi-r\ell\sin\theta\sin\phi\\ -\ell r\cos\phi\cos\theta-r\ell\sin\theta\sin\phi & \ell^2\cos^2\phi+\ell^2\sin^2\phi\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}$$

Total kinetic energy of M and m

$$\text{Total } KE=T=T(M)+T(m)=\frac{1}{2}\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}MR^2+mr^2 & -mr\ell\cos(\theta-\phi)\\ -mr\ell\cos(\theta-\phi) & m\ell^2\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}=\frac{1}{2}\left[(MR^2+mr^2)\dot{\theta}^2-2mr\ell\cos(\theta-\phi)\,\dot{\theta}\dot{\phi}+m\ell^2\dot{\phi}^2\right]$$

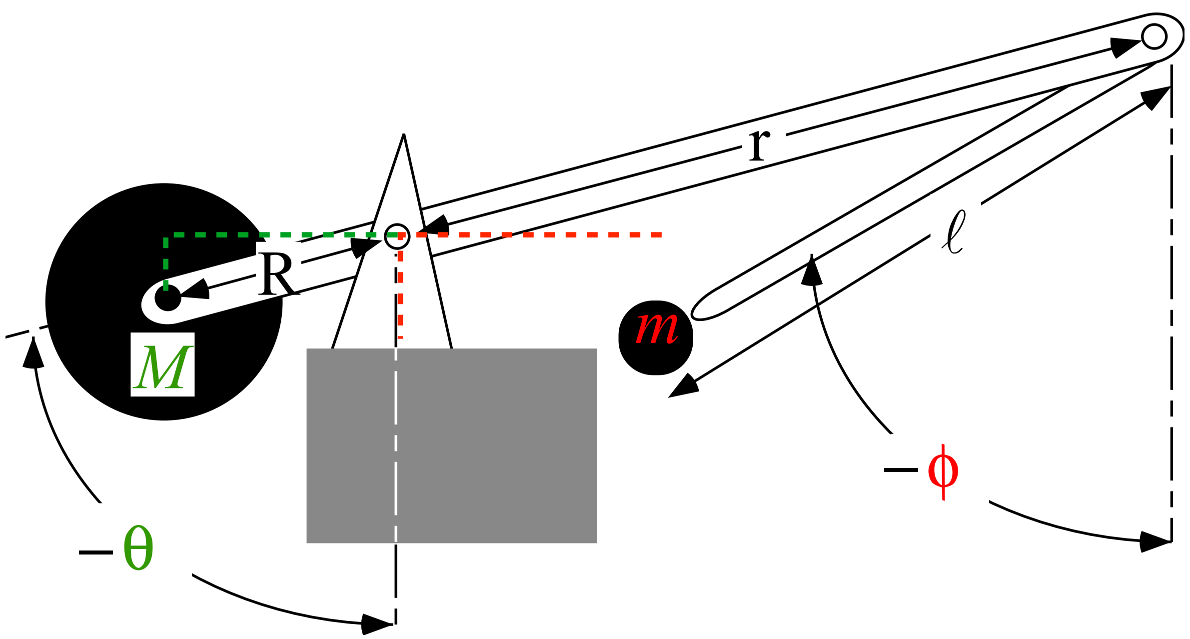
Dynamic metric tensor γ_{mn}

$$\begin{pmatrix}\gamma_{\theta,\theta} & \gamma_{\theta,\phi}\\ \gamma_{\phi,\theta} & \gamma_{\phi,\phi}\end{pmatrix}$$

$$\gamma_{mn}=\sum_{\text{mass }\mu}m(\mu)\frac{\partial x^j(\mu)}{\partial q^m}\frac{\partial x^j(\mu)}{\partial q^n}$$

$$=\sum_{\text{mass }\mu}m(\mu)\frac{\partial\mathbf{r}(\mu)}{\partial q^m}\bullet\frac{\partial\mathbf{r}(\mu)}{\partial q^n}$$

$$=\sum_{\text{mass }\mu}m(\mu)\mathbf{E_m}(\mu)\bullet\mathbf{E_n}(\mu)$$



$$KE=\sum_{\text{mass }\mu}\frac{1}{2}m(\mu)\dot{x}^j(\mu)\dot{x}^j(\mu)=\sum_{\text{mass }\mu}\frac{1}{2}m(\mu)\frac{\partial x^j(\mu)}{\partial q^m}\frac{\partial x^j(\mu)}{\partial q^n}\dot{q}^m\dot{q}^n$$

$$=\frac{1}{2}\gamma_{mn}\dot{q}^m\dot{q}^n$$

Kinetic energy of driver M

$$T(M)=\frac{1}{2}M\dot{X}^2+\frac{1}{2}M\dot{Y}^2$$

$$=\frac{1}{2}MR^2\dot{\theta}^2$$

Kinetic energy of projectile m

$$T(m)=\frac{1}{2}m\begin{pmatrix}\dot{x} & \dot{y}\end{pmatrix}\begin{pmatrix}\dot{x}\\ \dot{y}\end{pmatrix}=\frac{1}{2}m\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}\frac{\partial x}{\partial\theta} & \frac{\partial x}{\partial\phi}\\ \frac{\partial y}{\partial\theta} & \frac{\partial y}{\partial\phi}\end{pmatrix}^T\begin{pmatrix}\frac{\partial x}{\partial\theta} & \frac{\partial x}{\partial\phi}\\ \frac{\partial y}{\partial\theta} & \frac{\partial y}{\partial\phi}\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}$$

$$=\frac{1}{2}m\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}-r\cos\theta & -r\sin\theta\\ \ell\cos\phi & \ell\sin\phi\end{pmatrix}\begin{pmatrix}-r\cos\theta & \ell\cos\phi\\ -r\sin\theta & \ell\sin\phi\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}$$

$$=\frac{1}{2}m\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}r^2\cos^2\theta+r^2\sin^2\theta & -r\ell\cos\theta\cos\phi-r\ell\sin\theta\sin\phi\\ -\ell r\cos\phi\cos\theta-r\ell\sin\theta\sin\phi & \ell^2\cos^2\phi+\ell^2\sin^2\phi\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}$$

Total kinetic energy of M and m

$$\text{Total KE}=T=T(M)+T(m)=\frac{1}{2}\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}MR^2+mr^2 & -mr\ell\cos(\theta-\phi)\\ -mr\ell\cos(\theta-\phi) & m\ell^2\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}=\frac{1}{2}\left[(MR^2+mr^2)\dot{\theta}^2-2mr\ell\cos(\theta-\phi)\,\dot{\theta}\dot{\phi}+m\ell^2\dot{\phi}^2\right]$$

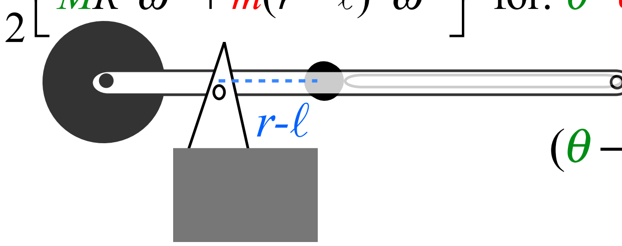
Dynamic metric tensor γ_{mn}

$$\begin{pmatrix}\gamma_{\theta,\theta} & \gamma_{\theta,\phi}\\ \gamma_{\phi,\theta} & \gamma_{\phi,\phi}\end{pmatrix}$$

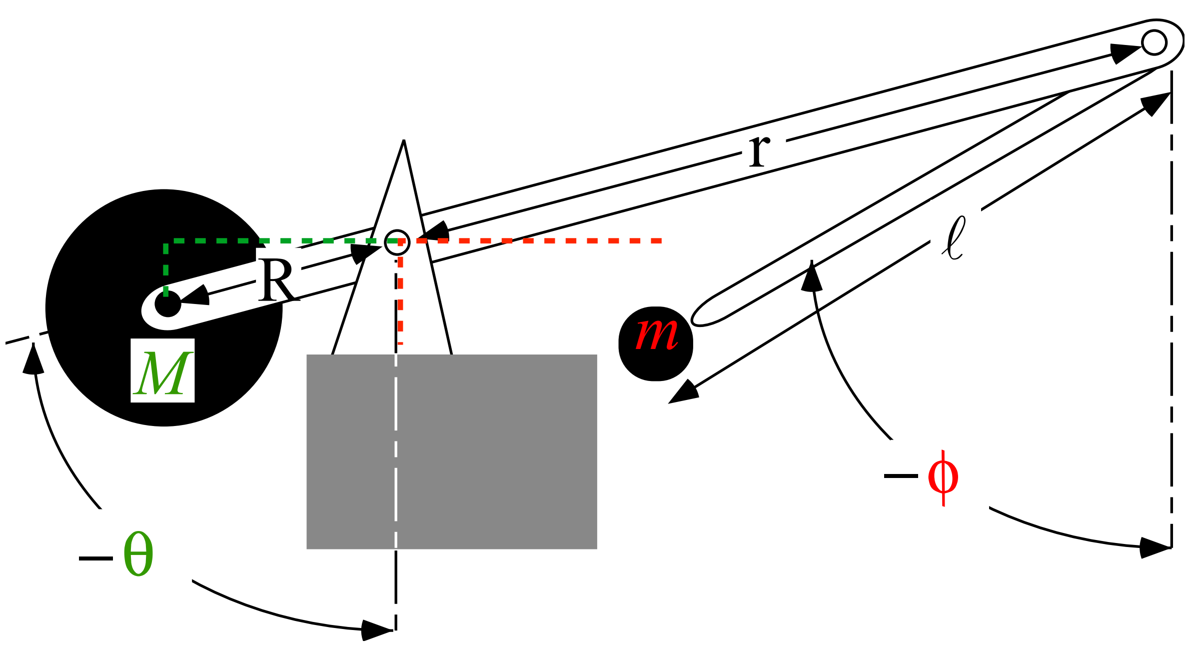
Special cases (rigid rotation)

$$T=\frac{1}{2}\left[MR^2\omega^2+m(r-\ell)^2\omega^2\right]\quad\text{for: }\dot{\theta}=\dot{\phi}=\omega\text{ and }(\theta-\phi)=0$$

(J is Singular)



$(\theta-\phi)=0$



Kinetic energy of driver M

$$T(M)=\frac{1}{2}M\dot{X}^2+\frac{1}{2}M\dot{Y}^2$$

$$=\frac{1}{2}MR^2\dot{\theta}^2$$

Kinetic energy of projectile m

$$T(m)=\frac{1}{2}m\begin{pmatrix}\dot{x} & \dot{y}\end{pmatrix}\begin{pmatrix}\dot{x}\\ \dot{y}\end{pmatrix}=\frac{1}{2}m\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}\frac{\partial x}{\partial\theta} & \frac{\partial x}{\partial\phi}\\ \frac{\partial y}{\partial\theta} & \frac{\partial y}{\partial\phi}\end{pmatrix}^T\begin{pmatrix}\frac{\partial x}{\partial\theta} & \frac{\partial x}{\partial\phi}\\ \frac{\partial y}{\partial\theta} & \frac{\partial y}{\partial\phi}\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}$$

$$=\frac{1}{2}m\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}-r\cos\theta & -r\sin\theta\\ \ell\cos\phi & \ell\sin\phi\end{pmatrix}\begin{pmatrix}-r\cos\theta & \ell\cos\phi\\ -r\sin\theta & \ell\sin\phi\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}$$

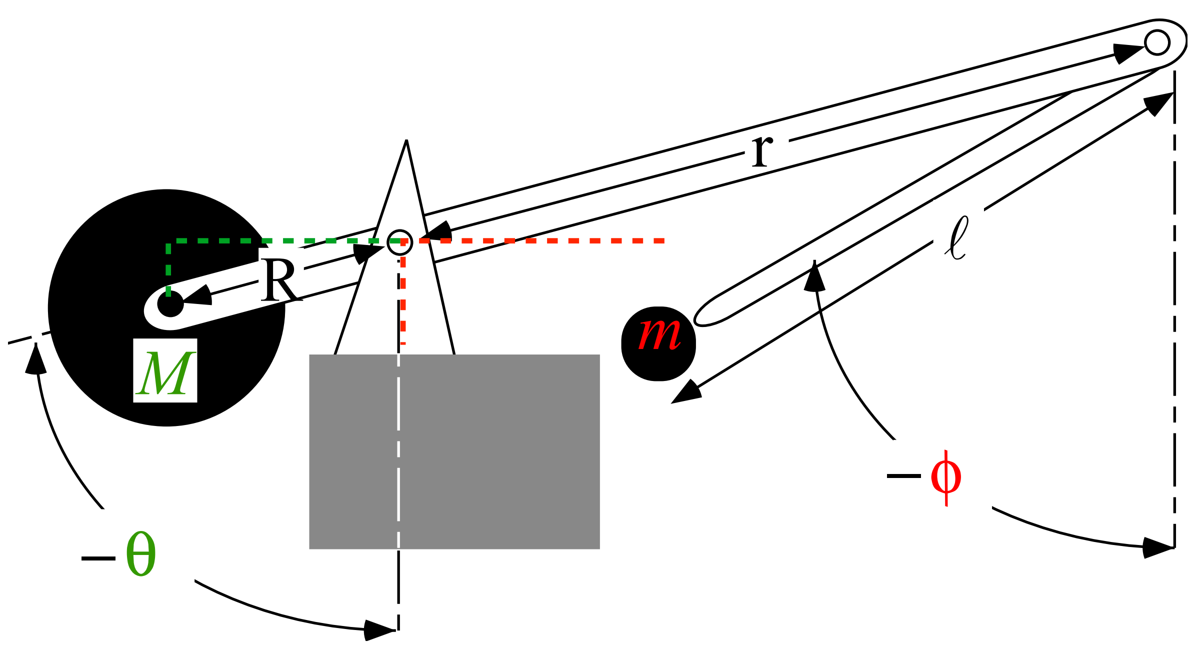
$$=\frac{1}{2}m\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}r^2\cos^2\theta+r^2\sin^2\theta & -r\ell\cos\theta\cos\phi-r\ell\sin\theta\sin\phi\\ -\ell r\cos\phi\cos\theta-r\ell\sin\theta\sin\phi & \ell^2\cos^2\phi+\ell^2\sin^2\phi\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}$$

Total kinetic energy of M and m

$$\text{Total KE}=T=T(M)+T(m)=\frac{1}{2}\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}MR^2+mr^2 & -mr\ell\cos(\theta-\phi)\\ -mr\ell\cos(\theta-\phi) & m\ell^2\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}=\frac{1}{2}\left[(MR^2+mr^2)\dot{\theta}^2-2mr\ell\cos(\theta-\phi)\,\dot{\theta}\dot{\phi}+m\ell^2\dot{\phi}^2\right]$$

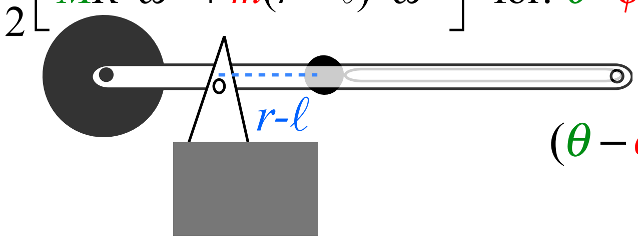
Dynamic metric tensor γ_{mn}

$$\begin{pmatrix}\gamma_{\theta,\theta} & \gamma_{\theta,\phi}\\ \gamma_{\phi,\theta} & \gamma_{\phi,\phi}\end{pmatrix}$$



Special cases (rigid rotation)

$$T=\frac{1}{2}\left[MR^2\omega^2+m(r-\ell)^2\omega^2\right]$$ for: $\dot{\theta}=\dot{\phi}=\omega$ and $(\theta-\phi)=0$

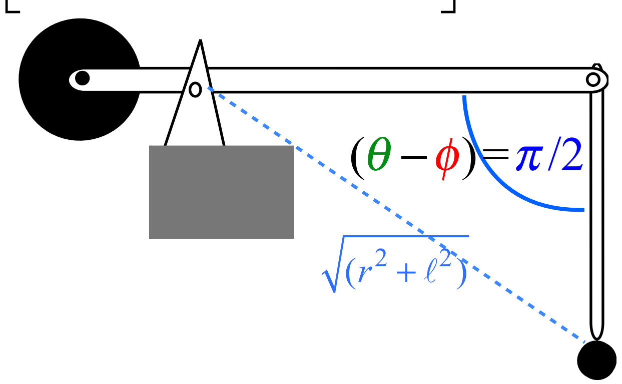


(J is Singular)

$(\theta-\phi)=0$

$$T=\frac{1}{2}\left[MR^2\omega^2+m(r^2+\ell^2)\omega^2\right]$$ for: $\dot{\theta}=\dot{\phi}=\omega$ and $(\theta-\phi)=\pi/2$

(J is Orthogonal)



Kinetic energy of driver M

$$T(M)=\frac{1}{2}M\dot{X}^2+\frac{1}{2}M\dot{Y}^2$$

$$=\frac{1}{2}MR^2\dot{\theta}^2$$

Kinetic energy of projectile m

$$T(m)=\frac{1}{2}m\begin{pmatrix}\dot{x} & \dot{y}\end{pmatrix}\begin{pmatrix}\dot{x}\\ \dot{y}\end{pmatrix}=\frac{1}{2}m\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}\frac{\partial x}{\partial\theta} & \frac{\partial x}{\partial\phi}\\ \frac{\partial y}{\partial\theta} & \frac{\partial y}{\partial\phi}\end{pmatrix}^T\begin{pmatrix}\frac{\partial x}{\partial\theta} & \frac{\partial x}{\partial\phi}\\ \frac{\partial y}{\partial\theta} & \frac{\partial y}{\partial\phi}\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}$$

$$=\frac{1}{2}m\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}-r\cos\theta & -r\sin\theta\\ \ell\cos\phi & \ell\sin\phi\end{pmatrix}\begin{pmatrix}-r\cos\theta & \ell\cos\phi\\ -r\sin\theta & \ell\sin\phi\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}$$

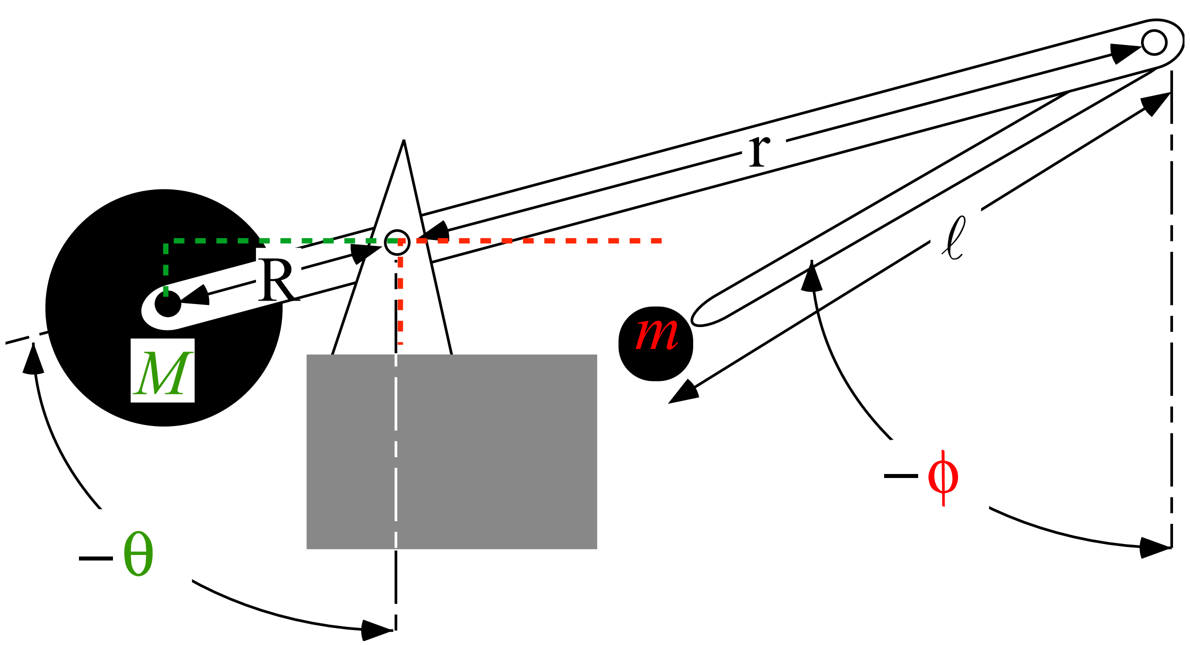
$$=\frac{1}{2}m\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}r^2\cos^2\theta+r^2\sin^2\theta & -r\ell\cos\theta\cos\phi-r\ell\sin\theta\sin\phi\\ -\ell r\cos\phi\cos\theta-r\ell\sin\theta\sin\phi & \ell^2\cos^2\phi+\ell^2\sin^2\phi\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}$$

Total kinetic energy of M and m

$$\text{Total KE}=T=T(M)+T(m)=\frac{1}{2}\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}MR^2+mr^2 & -mr\ell\cos(\theta-\phi)\\ -mr\ell\cos(\theta-\phi) & m\ell^2\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}=\frac{1}{2}\left[(MR^2+mr^2)\dot{\theta}^2-2mr\ell\cos(\theta-\phi)\,\dot{\theta}\dot{\phi}+m\ell^2\dot{\phi}^2\right]$$

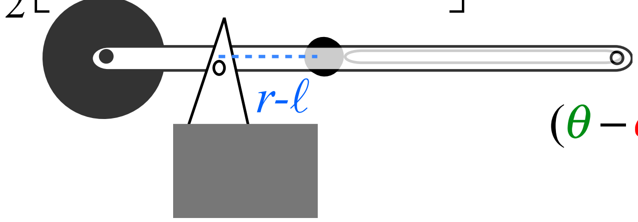
Dynamic metric tensor γ_{mn}

$$\begin{pmatrix}\gamma_{\theta,\theta} & \gamma_{\theta,\phi}\\ \gamma_{\phi,\theta} & \gamma_{\phi,\phi}\end{pmatrix}$$



Special cases (rigid rotation)

$$T=\frac{1}{2}\left[MR^2\omega^2+m(r-\ell)^2\omega^2\right]$$ for: $\dot{\theta}=\dot{\phi}=\omega$ and $(\theta-\phi)=0$

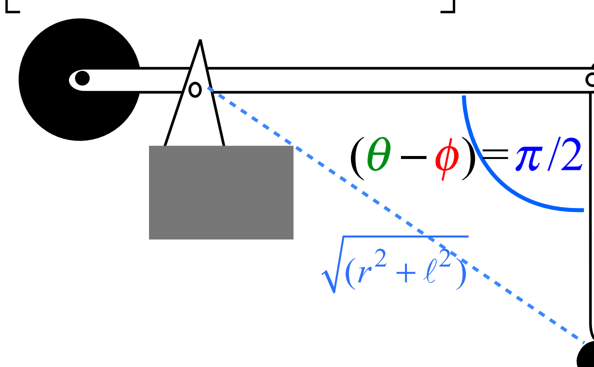


(J is Singular)

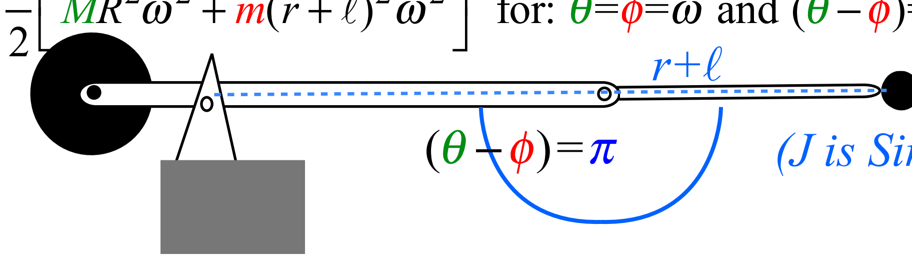
$(\theta-\phi)=0$

$$T=\frac{1}{2}\left[MR^2\omega^2+m(r^2+\ell^2)\omega^2\right]$$ for: $\dot{\theta}=\dot{\phi}=\omega$ and $(\theta-\phi)=\pi/2$

(J is Orthogonal)



$$T=\frac{1}{2}\left[MR^2\omega^2+m(r+\ell)^2\omega^2\right]$$ for: $\dot{\theta}=\dot{\phi}=\omega$ and $(\theta-\phi)=\pi$



(J is Singular)

Kinetic energy of driver M

$$T(M)=\frac{1}{2}M\dot{X}^2+\frac{1}{2}M\dot{Y}^2$$

$$=\frac{1}{2}MR^2\dot{\theta}^2$$

Kinetic energy of projectile m

$$T(m)=\frac{1}{2}m\begin{pmatrix}\dot{x} & \dot{y}\end{pmatrix}\begin{pmatrix}\dot{x}\\ \dot{y}\end{pmatrix}=\frac{1}{2}m\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}\frac{\partial x}{\partial\theta} & \frac{\partial x}{\partial\phi}\\ \frac{\partial y}{\partial\theta} & \frac{\partial y}{\partial\phi}\end{pmatrix}^T\begin{pmatrix}\frac{\partial x}{\partial\theta} & \frac{\partial x}{\partial\phi}\\ \frac{\partial y}{\partial\theta} & \frac{\partial y}{\partial\phi}\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}$$

$$=\frac{1}{2}m\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}-r\cos\theta & -r\sin\theta\\ \ell\cos\phi & \ell\sin\phi\end{pmatrix}\begin{pmatrix}-r\cos\theta & \ell\cos\phi\\ -r\sin\theta & \ell\sin\phi\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}$$

$$=\frac{1}{2}m\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}r^2\cos^2\theta+r^2\sin^2\theta & -r\ell\cos\theta\cos\phi-r\ell\sin\theta\sin\phi\\ -\ell r\cos\phi\cos\theta-r\ell\sin\theta\sin\phi & \ell^2\cos^2\phi+\ell^2\sin^2\phi\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}$$

Total kinetic energy of M and m

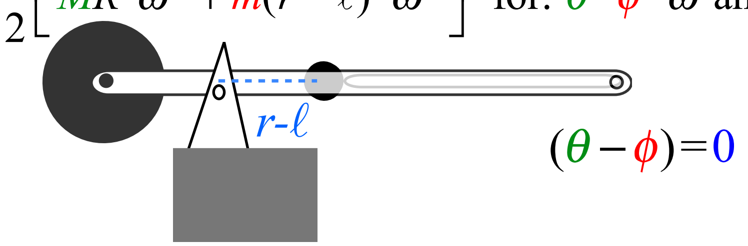
$$\text{Total KE}=T=T(M)+T(m)=\frac{1}{2}\begin{pmatrix}\dot{\theta} & \dot{\phi}\end{pmatrix}\begin{pmatrix}MR^2+mr^2 & -mr\ell\cos(\theta-\phi)\\ -mr\ell\cos(\theta-\phi) & m\ell^2\end{pmatrix}\begin{pmatrix}\dot{\theta}\\ \dot{\phi}\end{pmatrix}=\frac{1}{2}\left[(MR^2+mr^2)\dot{\theta}^2-2mr\ell\cos(\theta-\phi)\,\dot{\theta}\dot{\phi}+m\ell^2\dot{\phi}^2\right]$$

Dynamic metric tensor γ_{mn}

$$\begin{pmatrix}\gamma_{\theta,\theta} & \gamma_{\theta,\phi}\\ \gamma_{\phi,\theta} & \gamma_{\phi,\phi}\end{pmatrix}$$

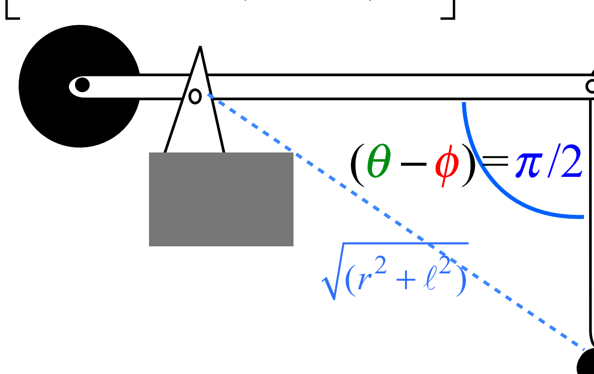
Special cases (rigid rotation)

$$T=\frac{1}{2}\left[MR^2\omega^2+m(r-\ell)^2\omega^2\right]\quad\text{for: }\dot{\theta}=\dot{\phi}=\omega\text{ and }(\theta-\phi)=0$$



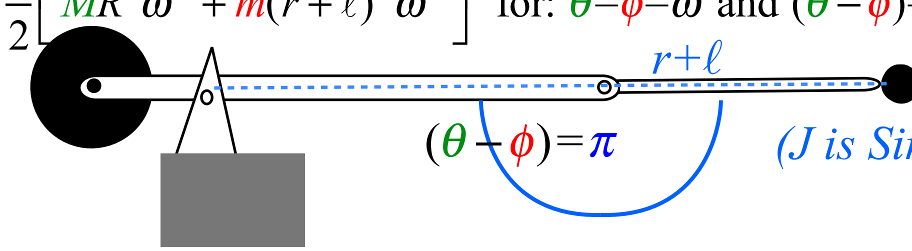
(J is Singular)

$$T=\frac{1}{2}\left[MR^2\omega^2+m(r^2+\ell^2)\omega^2\right]\quad\text{for: }\dot{\theta}=\dot{\phi}=\omega\text{ and }(\theta-\phi)=\pi/2$$



(J is Orthogonal)

$$T=\frac{1}{2}\left[MR^2\omega^2+m(r+\ell)^2\omega^2\right]\quad\text{for: }\dot{\theta}=\dot{\phi}=\omega\text{ and }(\theta-\phi)=\pi$$



(J is Singular)

(a) When (θ,φ) coordinates are orthogonal *(b) When (θ,φ) coordinates are not orthogonal*

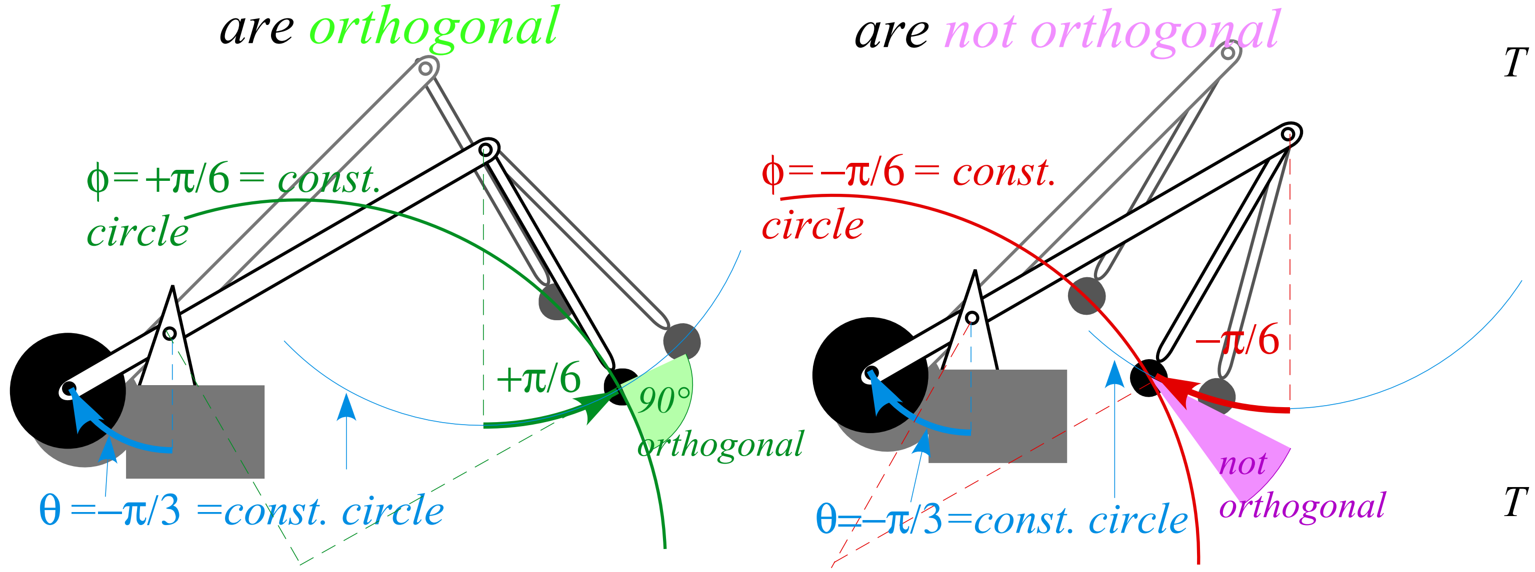


Fig. 2.3.1 Examples of (θ,φ) intersections (a) othogonal (special case), (b) non-orthogonal (typical).

Geometric and topological properties of GCC transformations (Mostly Unit 3.)

→ *Multivalued functionality and connections*

Covariant and contravariant relations

Metric tensors

Trebuchet Cartesian projectile coordinates are double-valued

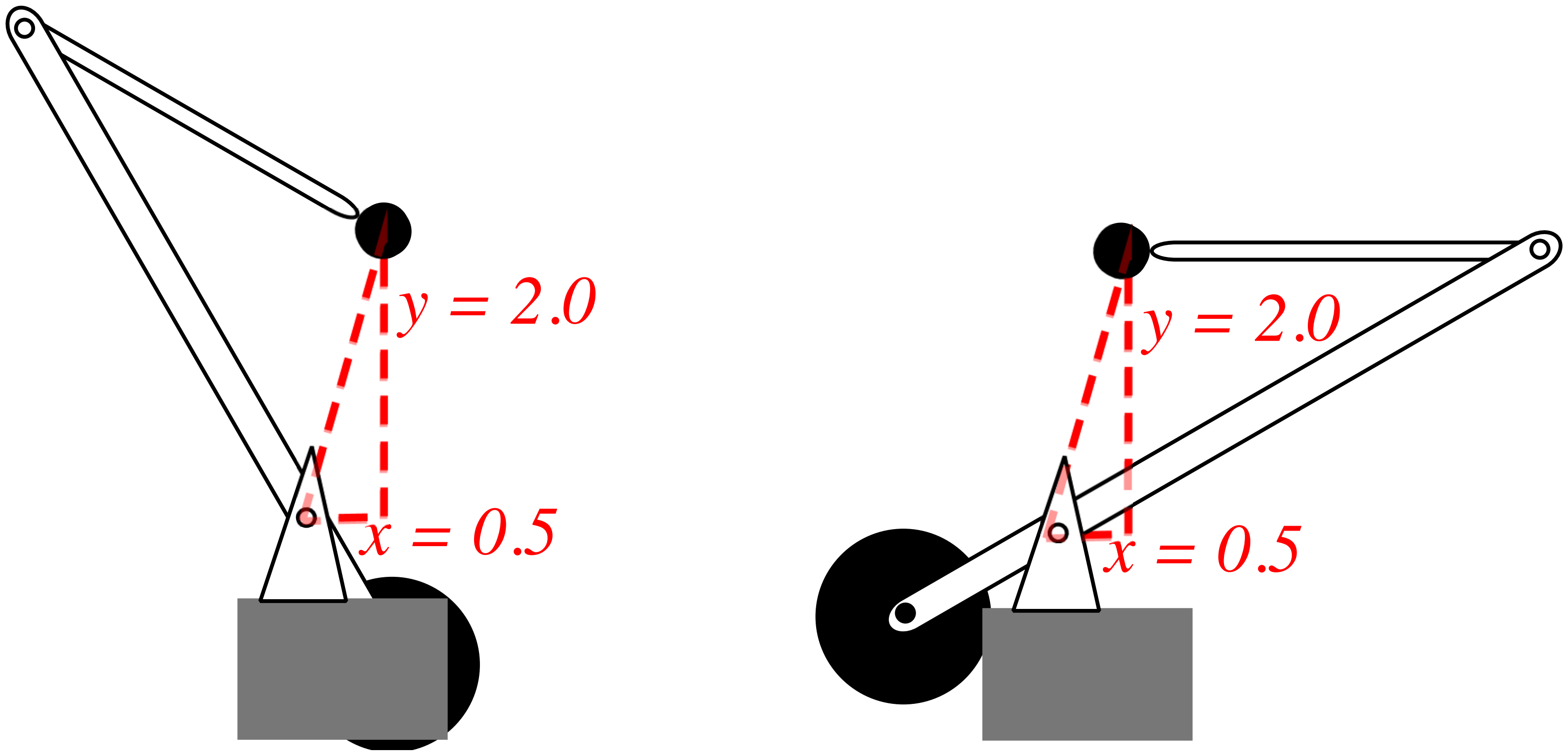


Fig. 2.2.3 Trebuchet configurations with the same coordinates x and y of projectile *m*.

Trebuchet Cartesian projectile coordinates are double-valued…(Belong to 2 distinct manifolds)

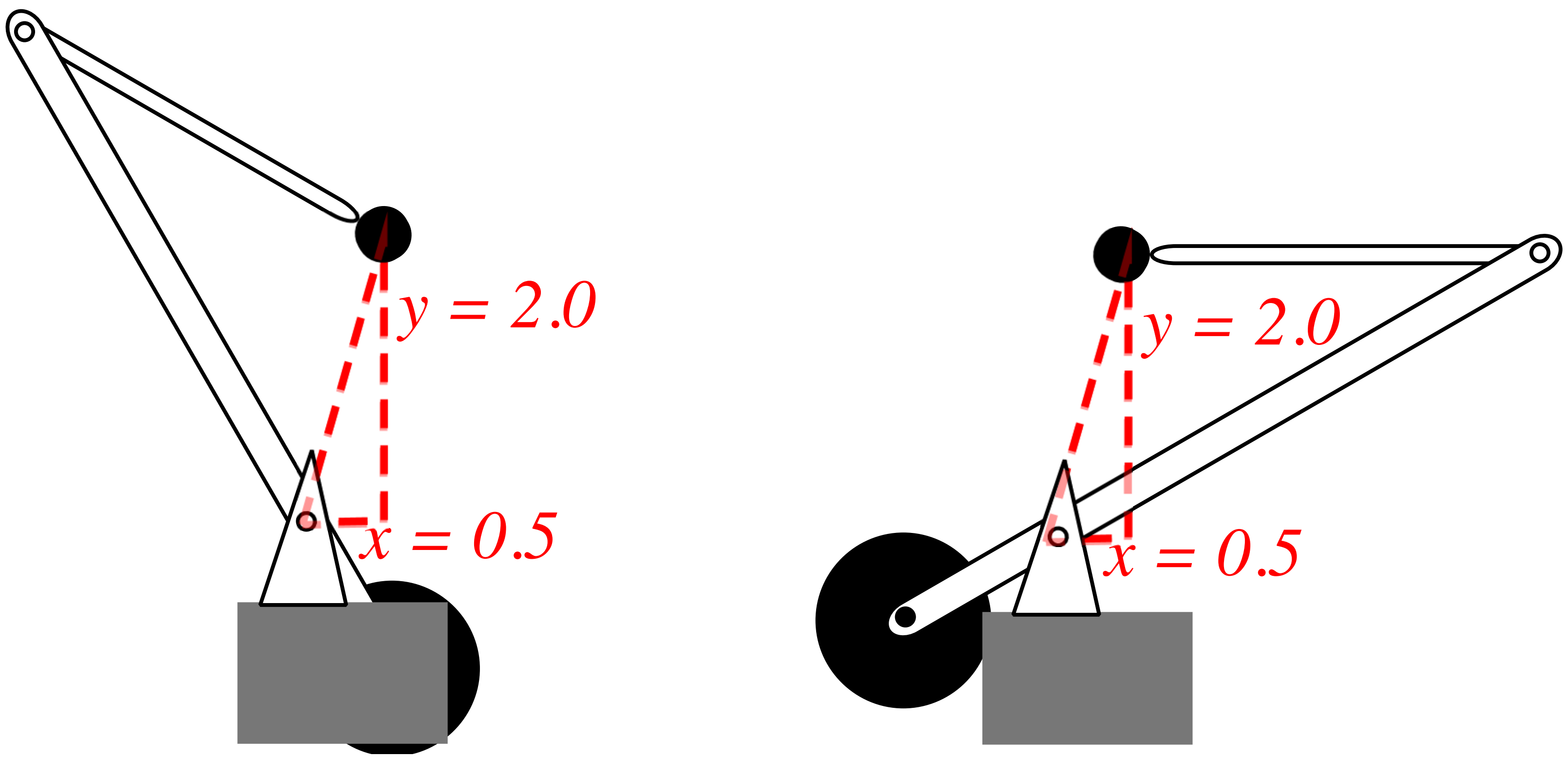


Fig. 2.2.3 Trebuchet configurations with the same coordinates x and y of projectile *m*.

So, for example, are polar coordinates … (for each angle there are two r-values)

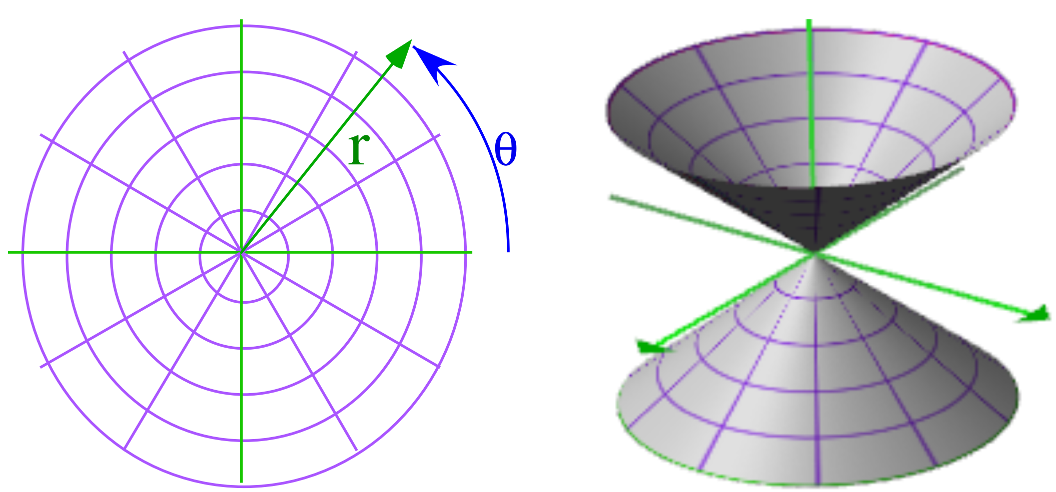


Fig. 3.1.4 Polar coordinates and possible embedding space on conical surface.

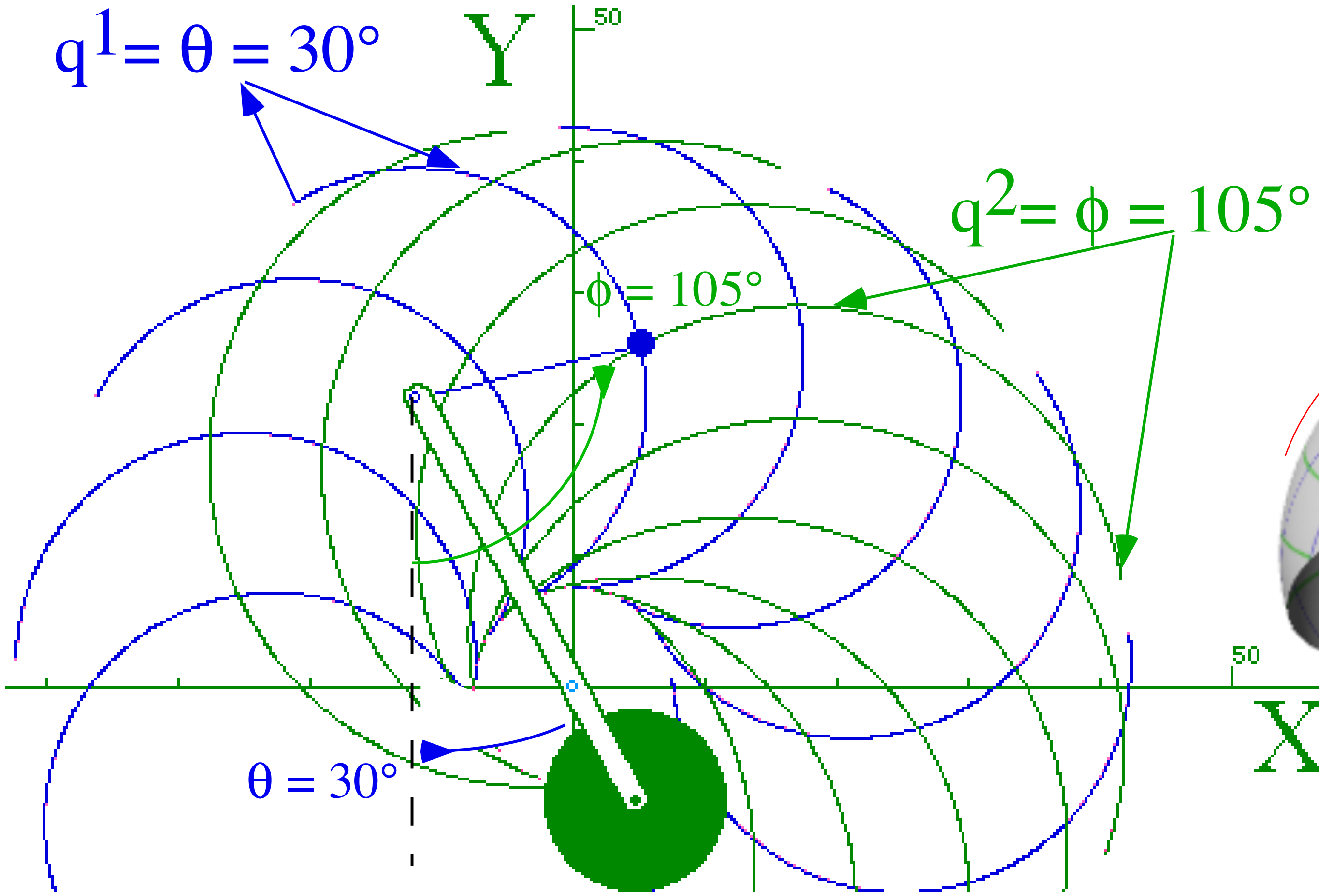


Fig. 3.1.1a (q^1=θ, q^2=ϕ)Coordinate manifold for trebuchet (Left handed sheet.)

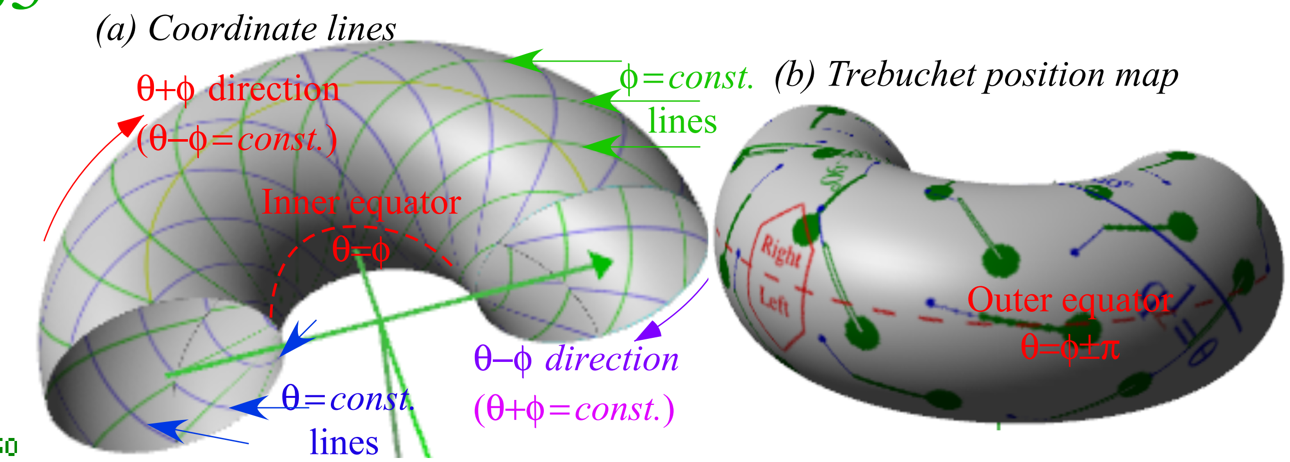


Fig. 3.1.2 Trebuchet torus.

(a) (q^1=θ, q^2=ϕ) coordinate lines. (b)Trebuchet position map and equators.

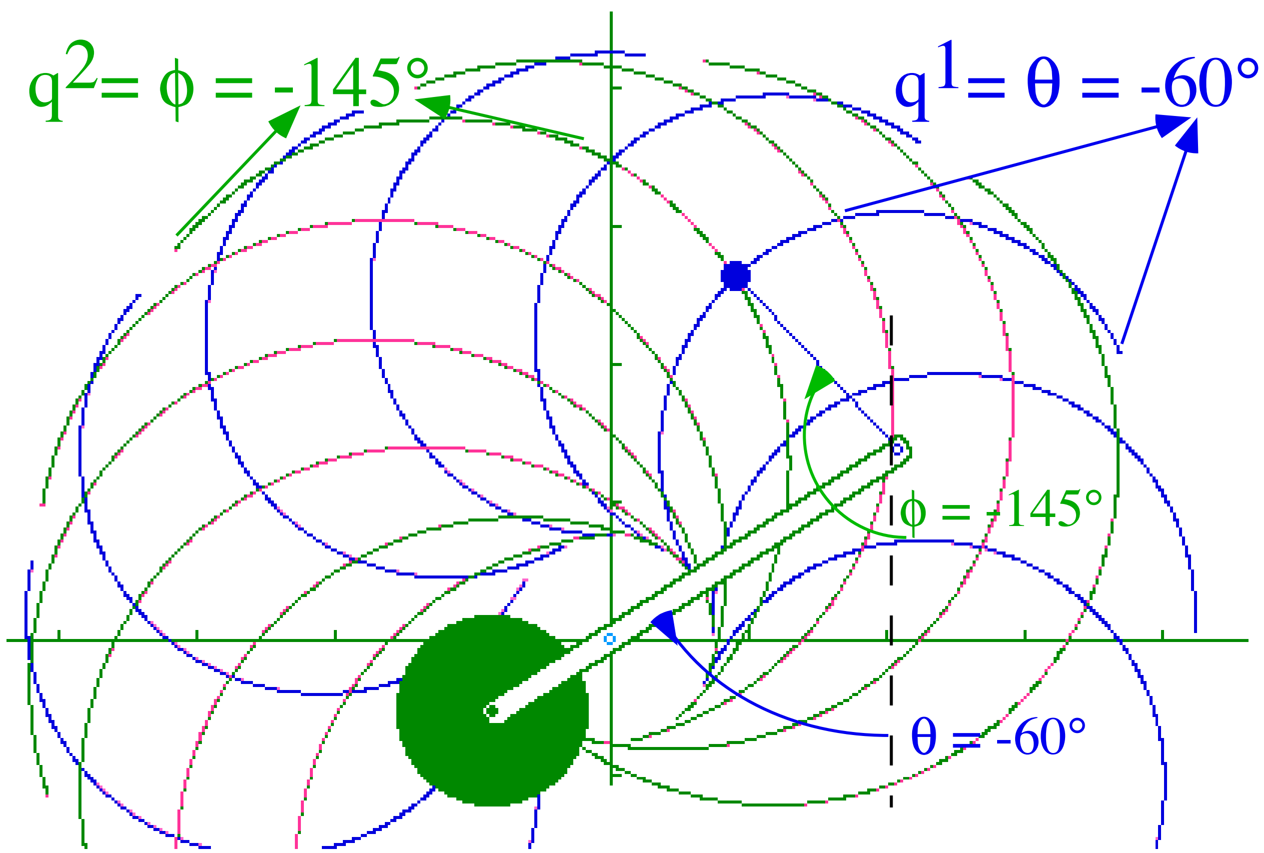
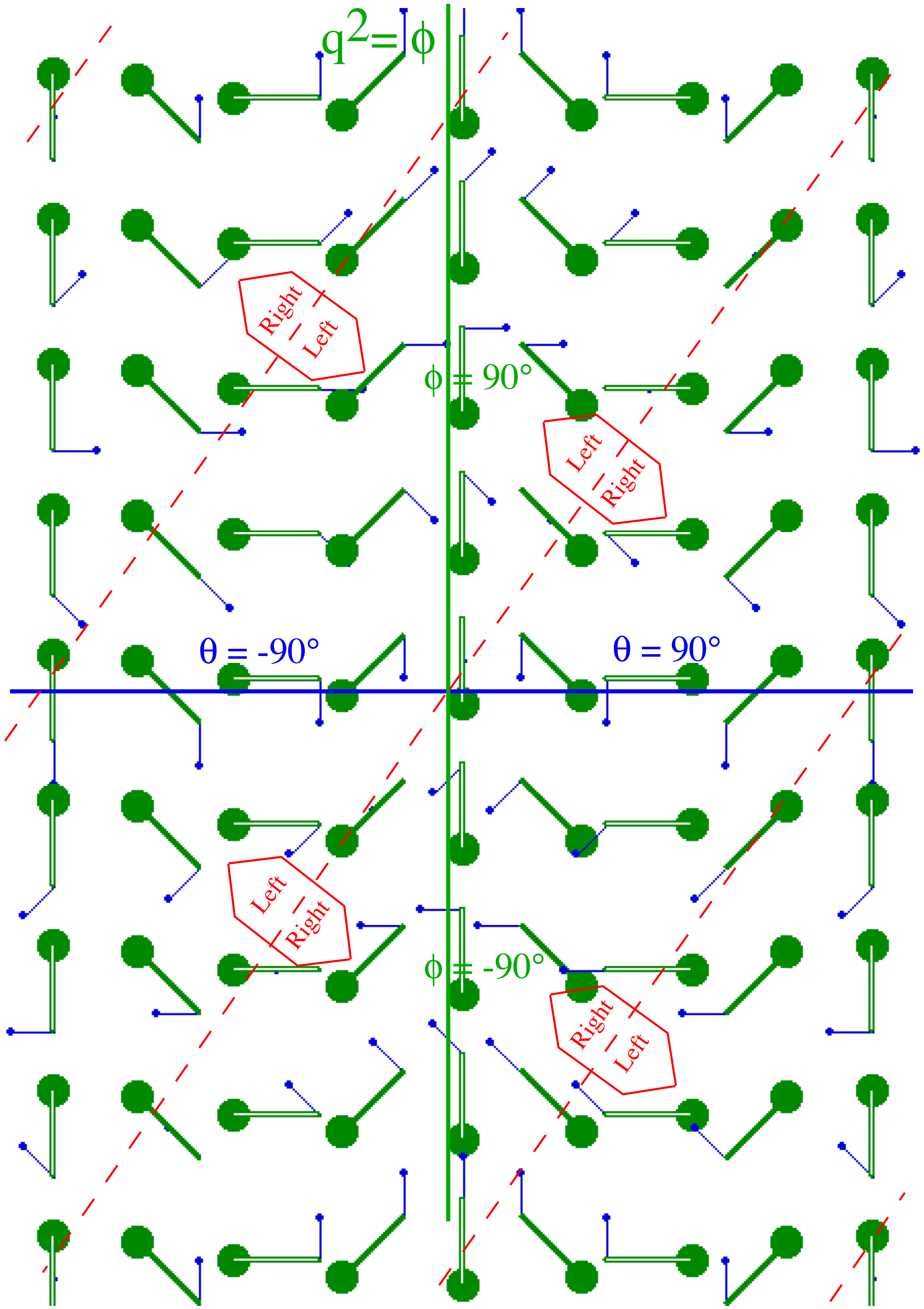


Fig. 3.1.1b (q^1=θ, q^2=ϕ)Coordinate manifold for trebuchet (Right handed sheet.)



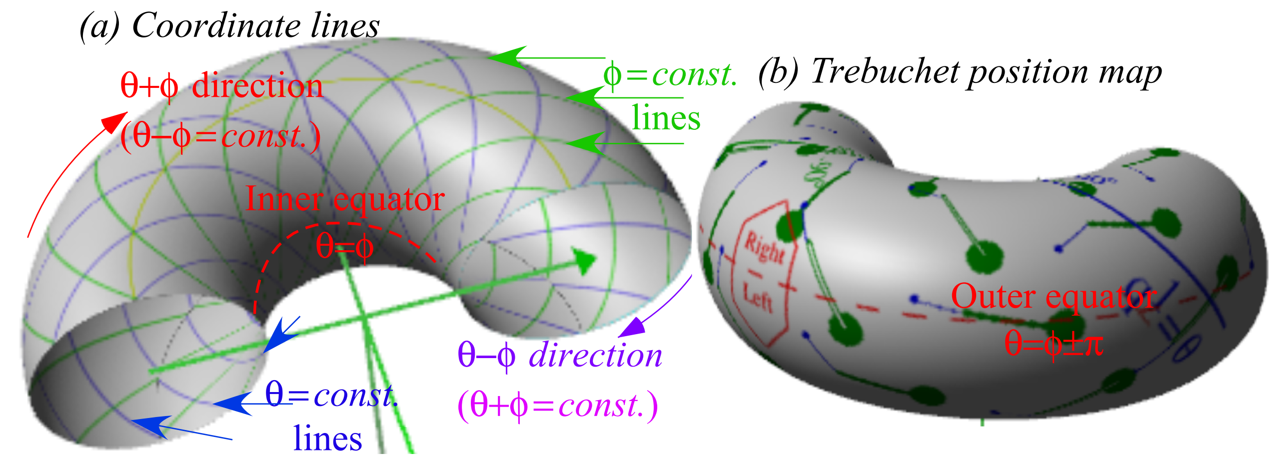


Fig. 3.1.2 Trebuchet torus.
(a) ($q^1=\theta$, $q^2=\phi$) coordinate lines.(b)Trebuchet position map and equators.

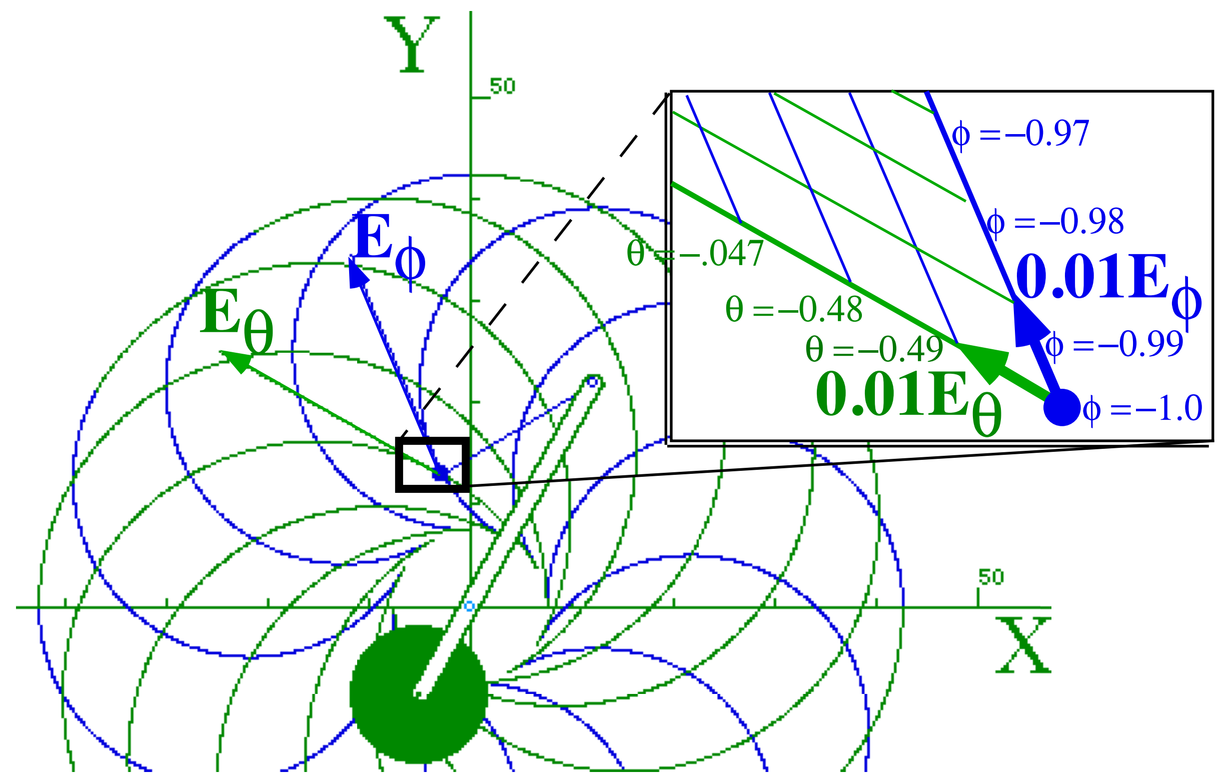


Fig. 3.2.2 Example of covariant unitary vectors and their tangent space.

Fig. 3.1.3 "Flattened" ($q^1=\theta$, $q^2=\phi$) coordinate manifold for trebuchet

Geometric and topological properties of GCC transformations (Mostly Unit 3.)

Multivalued functionality and connections

→ *Covariant and contravariant relations*

Metric tensors

Kajobian transfomation matrix *versus* *Jacobian transformation matrix*

$$\left\langle \frac{\partial q^m}{\partial x^j} \right\rangle =$$

$$\left|\begin{array}{ccc} \frac{\partial q^1}{\partial x^1} & \frac{\partial q^1}{\partial x^2} & \cdots \\ \frac{\partial q^2}{\partial x^1} & \frac{\partial q^2}{\partial x^2} & \cdots \\ \vdots & \vdots & \ddots \end{array}\right| \begin{array}{c} \mathbf{E}^1 \\ \mathbf{E}^2 \\ \vdots \end{array} = \begin{pmatrix} \frac{\partial \theta}{\partial x} & \frac{\partial \theta}{\partial y} \\ \frac{\partial \phi}{\partial x} & \frac{\partial \phi}{\partial y} \end{pmatrix} = \frac{\left|\begin{array}{cc} \ell \sin\phi & -\ell\cos\phi \\ r\sin\theta & -r\cos\theta \end{array}\right| \begin{array}{c} \mathbf{E}^\theta \\ \mathbf{E}^\phi \end{array}}{r\ell \sin(\theta - \phi)}$$

$$\left\langle \frac{\partial x^j}{\partial q^m} \right\rangle =$$

$$\left|\begin{array}{ccc} \mathbf{E}_1 & \mathbf{E}_2 & \cdots \\ \hline \frac{\partial x^1}{\partial q^1} & \frac{\partial x^1}{\partial q^2} & \cdots \\ \frac{\partial x^2}{\partial q^1} & \frac{\partial x^2}{\partial q^2} & \cdots \\ \vdots & \vdots & \ddots \end{array}\right| = \begin{pmatrix} \frac{\partial x}{\partial \theta} & \frac{\partial x}{\partial \phi} \\ \frac{\partial y}{\partial \theta} & \frac{\partial y}{\partial \phi} \end{pmatrix} = \left|\begin{array}{cc} \mathbf{E}_\theta & \mathbf{E}_\phi \\ \hline -r\cos\theta & \ell\cos\phi \\ -r\sin\theta & \ell\sin\phi \end{array}\right|$$

Contravariant vectors $\mathbf{E}^m$ *versus* *Covariant vectors* $\mathbf{E}_n$

$$\mathbf{E}^\theta = \begin{pmatrix} \ell\sin\phi & -\ell\cos\phi \end{pmatrix} / r\ell\sin(\theta - \phi)$$

$$\mathbf{E}^\phi = \begin{pmatrix} r\sin\theta & -r\cos\theta \end{pmatrix} / r\ell\sin(\theta - \phi)$$

$$\mathbf{E}_\theta = \begin{pmatrix} -r\cos\theta \\ -r\sin\theta \end{pmatrix}, \quad \mathbf{E}_\phi = \begin{pmatrix} \ell\cos\phi \\ \ell\sin\phi \end{pmatrix}$$

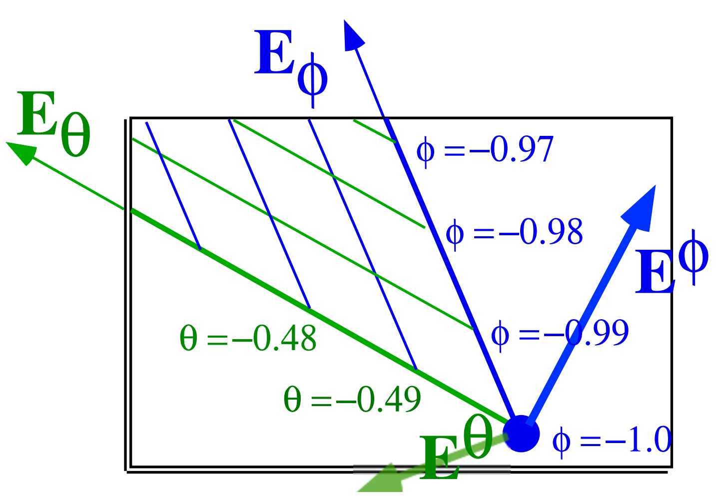


Fig. 3.2.3 Example of contravariant unitary vectors and their normal space.

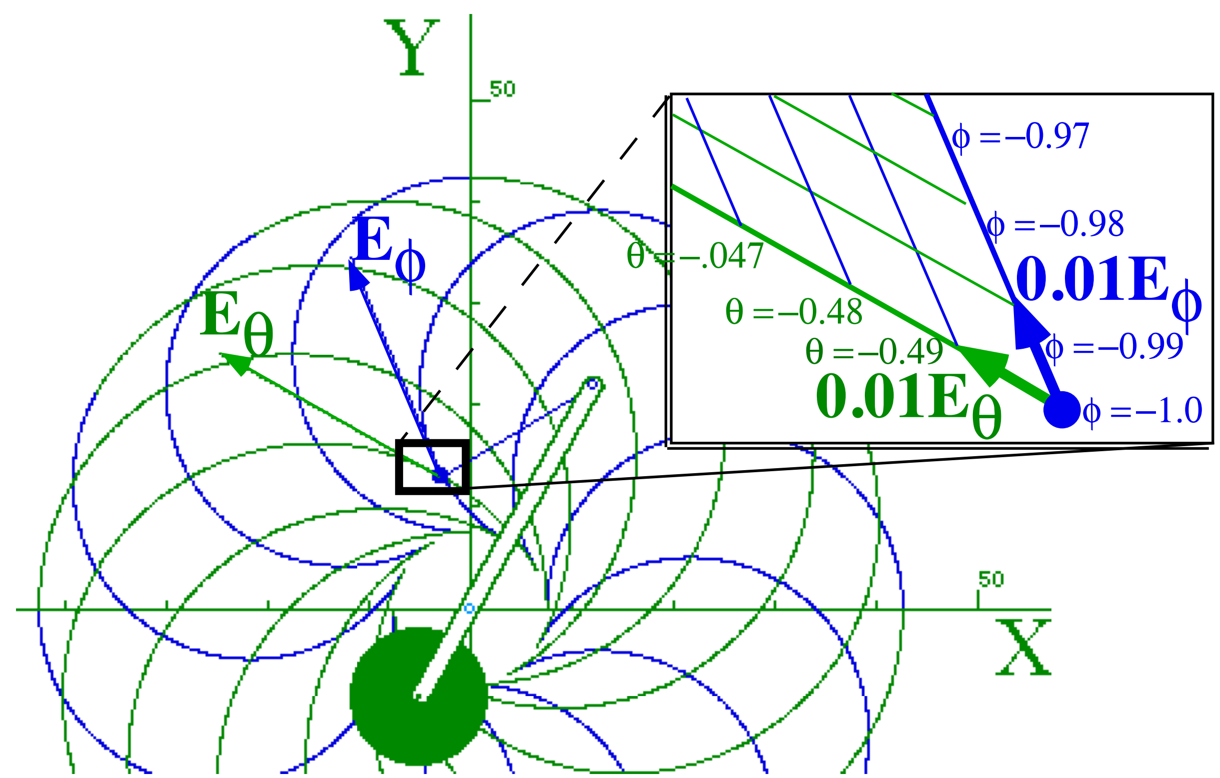


Fig. 3.2.2 Example of covariant unitary vectors and their tangent space.

Contravariant vectors $\mathbf{E}^m$ *versus* *Covariant vectors* $\mathbf{E}_n$

Any vector **U**,**V**,**...** is expressed using *either* set from any viewpoint, coordinate system, or *frame*,

$$\mathbf{U} = U^m\,\mathbf{E_m} = U_n\,\mathbf{E^n} = \bar{U}^{\bar{m}}\,\bar{\mathbf{E}}_{\bar{\mathbf{m}}} = \bar{U}_{\bar{n}}\,\bar{\mathbf{E}}^{\bar{\mathbf{n}}} \qquad \mathbf{V} = V^m\,\mathbf{E_m} = V_n\,\mathbf{E^n} = \bar{V}^{\bar{m}}\,\bar{\mathbf{E}}_{\bar{\mathbf{m}}} = \bar{V}_{\bar{n}}\,\bar{\mathbf{E}}^{\bar{\mathbf{n}}}$$

where the *Um, Vm,...are contravariant components* and the *Un , Vn ,...are covariant components*

$U^m = \mathbf{U}\bullet\mathbf{E^m}$, $V^m = \mathbf{V}\bullet\mathbf{E^m}$, and $\bar{U}^{\bar{m}} = \mathbf{U}\bullet\bar{\mathbf{E}}^{\bar{\mathbf{m}}}$, $\bar{V}^{\bar{m}} = \mathbf{V}\bullet\bar{\mathbf{E}}^{\bar{\mathbf{m}}}$, , $U_n = \mathbf{U}\bullet\mathbf{E_n}$, $V_n = \mathbf{V}\bullet\mathbf{E_n}$, and $\bar{U}_{\bar{n}} = \mathbf{U}\bullet\,\bar{\mathbf{E}}_{\bar{\mathbf{n}}}$, *etc.*

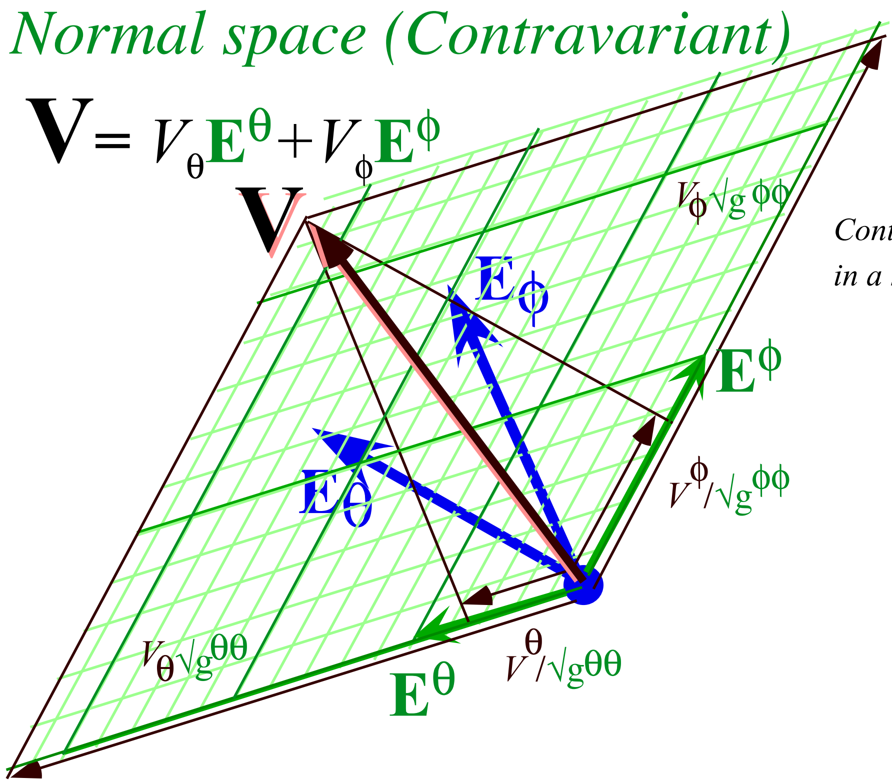


Fig. 3.3.2
Contravariant vector geometry in a normal space ($\mathbf{E}^\theta,\mathbf{E}^\phi$).

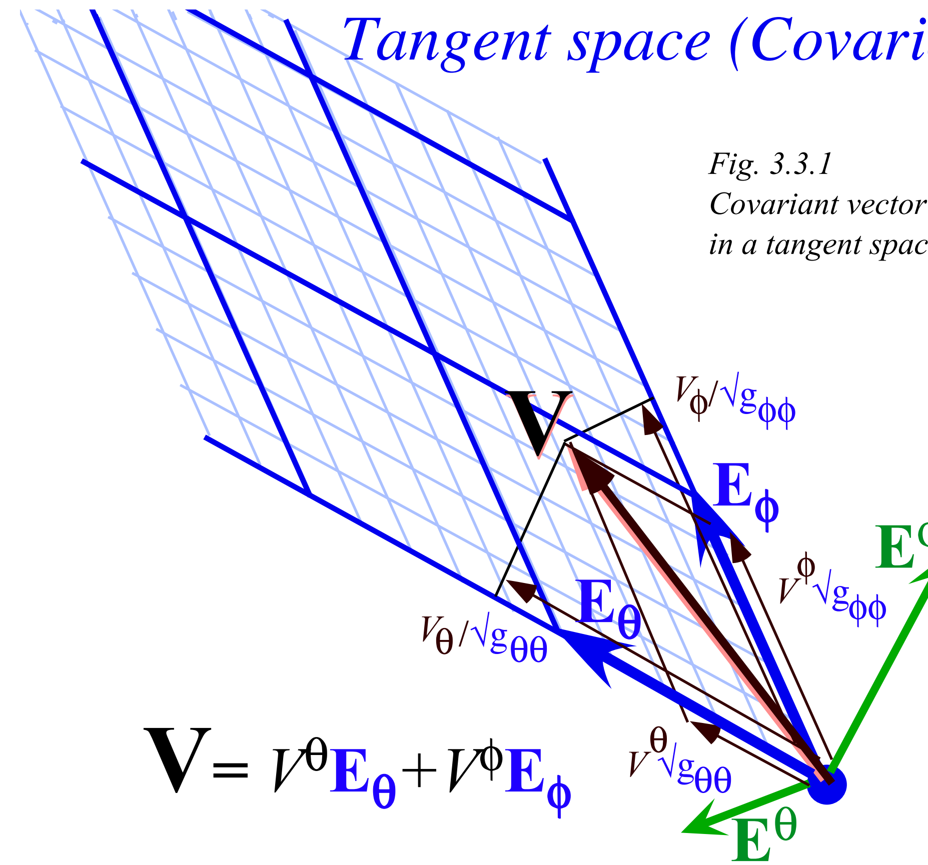


Fig. 3.3.1
Covariant vector geometry in a tangent space ($\mathbf{E}_\theta,\mathbf{E}_\phi$).

Contravariant vectors $\mathbf{E}^m$ *versus* *Covariant vectors* $\mathbf{E}_n$

Any vector **U**,**V**,**...** is expressed using *either* set from any viewpoint, coordinate system, or *frame*,

$$\mathbf{U} = U^m \mathbf{E_m} = U_n \mathbf{E^n} = \bar{U}^{\bar{m}} \bar{\mathbf{E}}_{\bar{\mathbf{m}}} = \bar{U}_{\bar{n}} \bar{\mathbf{E}}^{\bar{\mathbf{n}}} \qquad \mathbf{V} = V^m \mathbf{E_m} = V_n \mathbf{E^n} = \bar{V}^{\bar{m}} \bar{\mathbf{E}}_{\bar{\mathbf{m}}} = \bar{V}_{\bar{n}} \bar{\mathbf{E}}^{\bar{\mathbf{n}}}$$

where the *Um, Vm,...are contravariant components* and the *Un , Vn ,...are covariant components*

$$U^m = \mathbf{U} \bullet \mathbf{E^m},\ V^m = \mathbf{V} \bullet \mathbf{E^m},\ \text{and}\ \bar{U}^{\bar{m}} = \mathbf{U} \bullet \bar{\mathbf{E}}^{\bar{\mathbf{m}}},\ \bar{V}^{\bar{m}} = \mathbf{V} \bullet \bar{\mathbf{E}}^{\bar{\mathbf{m}}},\ , \qquad U_n = \mathbf{U} \bullet \mathbf{E_n},\ V_n = \mathbf{V} \bullet \mathbf{E_n},\ \text{and}\ \bar{U}_{\bar{n}} = \mathbf{U} \bullet \bar{\mathbf{E}}_{\bar{\mathbf{n}}},\ etc.$$

Normal space (Contravariant)

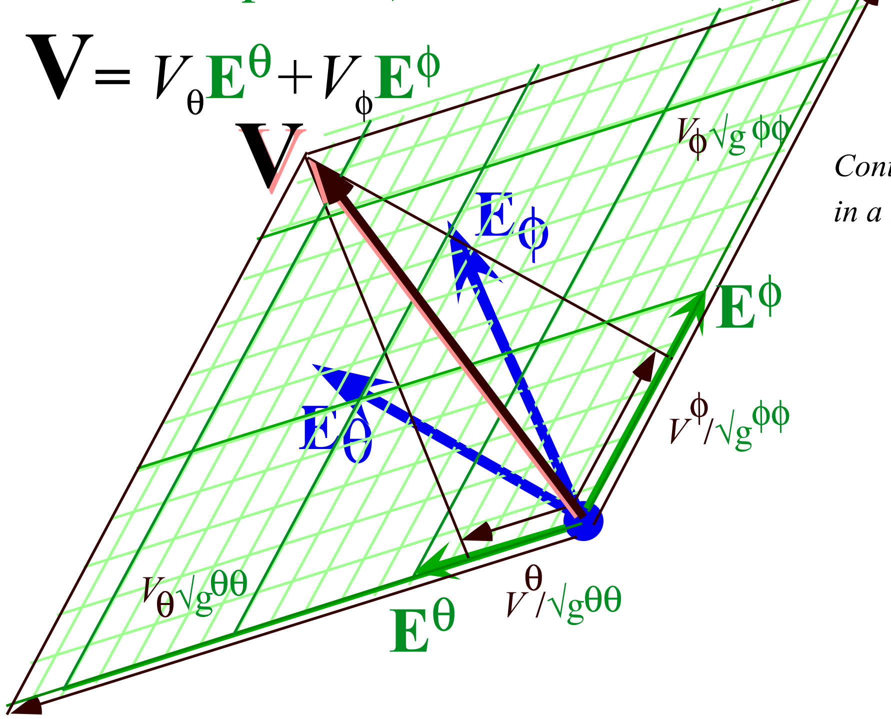


Fig. 3.3.2
Contravariant vector geometry in a normal space ($\mathbf{E}^\theta, \mathbf{E}^\phi$).

Tangent space (Covariant)

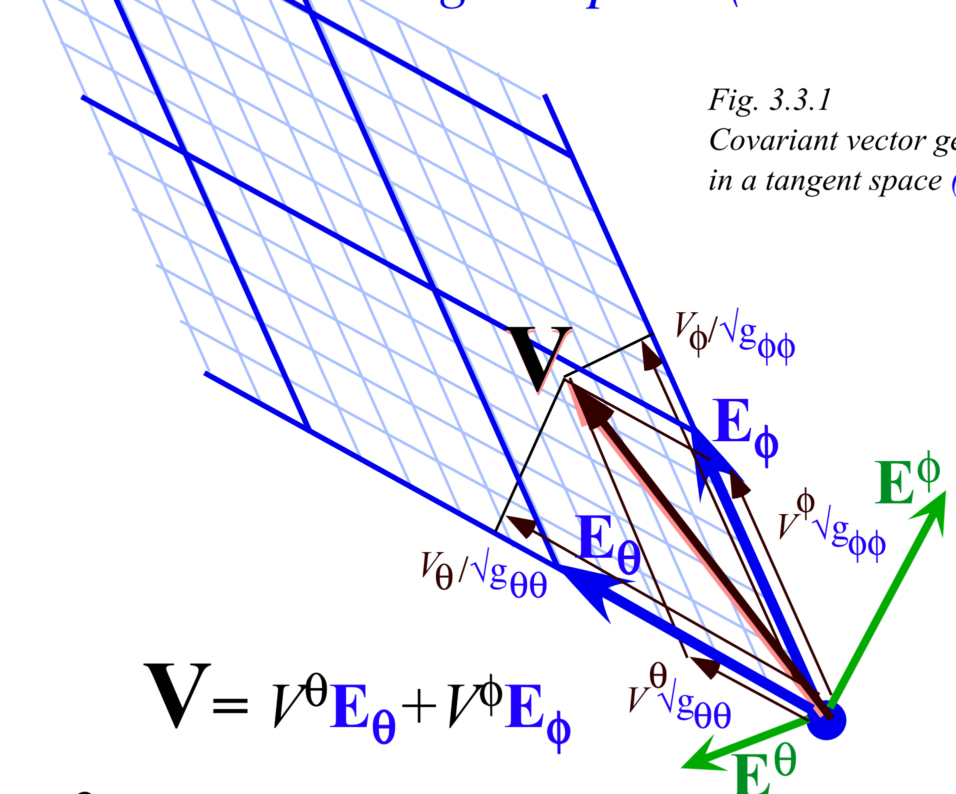


Fig. 3.3.1
Covariant vector geometry in a tangent space ($\mathbf{E}_\theta, \mathbf{E}_\phi$).

Contravariant vector $\mathbf{E^m}$ for frame $\{q^1, q^2, \cdots\}$ is written in terms of new vectors $\bar{\mathbf{E}}^{\bar{\mathbf{m}}}$ for a new "barred" frame $\{\bar{q}^1, \bar{q}^2, \cdots\}$ using a *"chain-saw-sum rule"*….

$$\mathbf{E^m} = \frac{\partial q^m}{\partial \mathbf{r}} = \frac{\partial q^m}{\quad} \frac{\quad}{\partial \mathbf{r}} = \frac{\partial q^m}{\partial \bar{q}^{\bar{m}}} \frac{\partial \bar{q}^{\bar{m}}}{\partial \mathbf{r}}, \quad \text{or:} \quad \boxed{\mathbf{E^m} = \frac{\partial q^m}{\partial \bar{q}^{\bar{m}}} \bar{\mathbf{E}}^{\bar{\mathbf{m}}}}$$

Contravariant vectors $\mathbf{E}^m$ *versus* *Covariant vectors* $\mathbf{E}_n$

Any vector **U,V,...** is expressed using *either* set from any viewpoint, coordinate system, or *frame*,

$$\mathbf{U} = U^m\,\mathbf{E_m} = U_n\,\mathbf{E^n} = \bar{U}^{\bar{m}}\,\bar{\mathbf{E}}_{\bar{\mathbf{m}}} = \bar{U}_{\bar{n}}\,\bar{\mathbf{E}}^{\bar{\mathbf{n}}} \qquad \mathbf{V} = V^m\,\mathbf{E_m} = V_n\,\mathbf{E^n} = \bar{V}^{\bar{m}}\,\bar{\mathbf{E}}_{\bar{\mathbf{m}}} = \bar{V}_{\bar{n}}\,\bar{\mathbf{E}}^{\bar{\mathbf{n}}}$$

where the *Um, Vm,...are contravariant components*

$$U^m = \mathbf{U}\bullet\mathbf{E^m},\; V^m = \mathbf{V}\bullet\mathbf{E^m},\;\text{and}\; \bar{U}^{\bar{m}} = \mathbf{U}\bullet\bar{\mathbf{E}}^{\bar{\mathbf{m}}},\; \bar{V}^{\bar{m}} = \mathbf{V}\bullet\bar{\mathbf{E}}^{\bar{\mathbf{m}}},\,,$$

and the *Un , Vn ,...are covariant components*

$$U_n = \mathbf{U}\bullet\mathbf{E_n},\; V_n = \mathbf{V}\bullet\mathbf{E_n},\;\text{and}\; \bar{U}_{\bar{n}} = \mathbf{U}\bullet\bar{\mathbf{E}}_{\bar{\mathbf{n}}},\; etc.$$

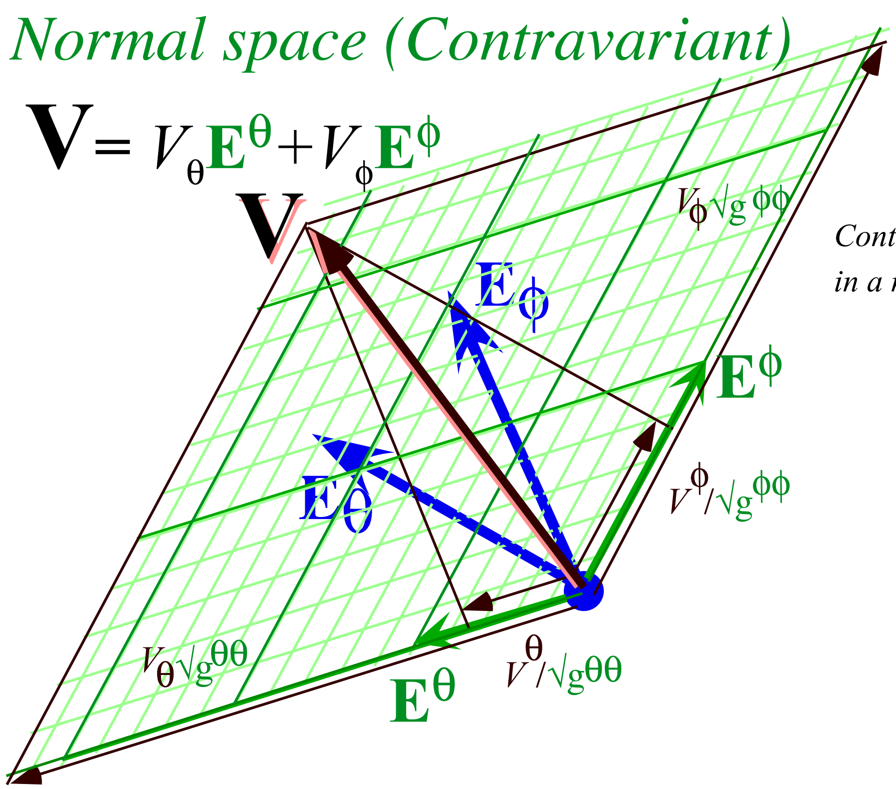


Fig. 3.3.2
Contravariant vector geometry
in a normal space ($\mathbf{E}^\theta, \mathbf{E}^\phi$ *).*

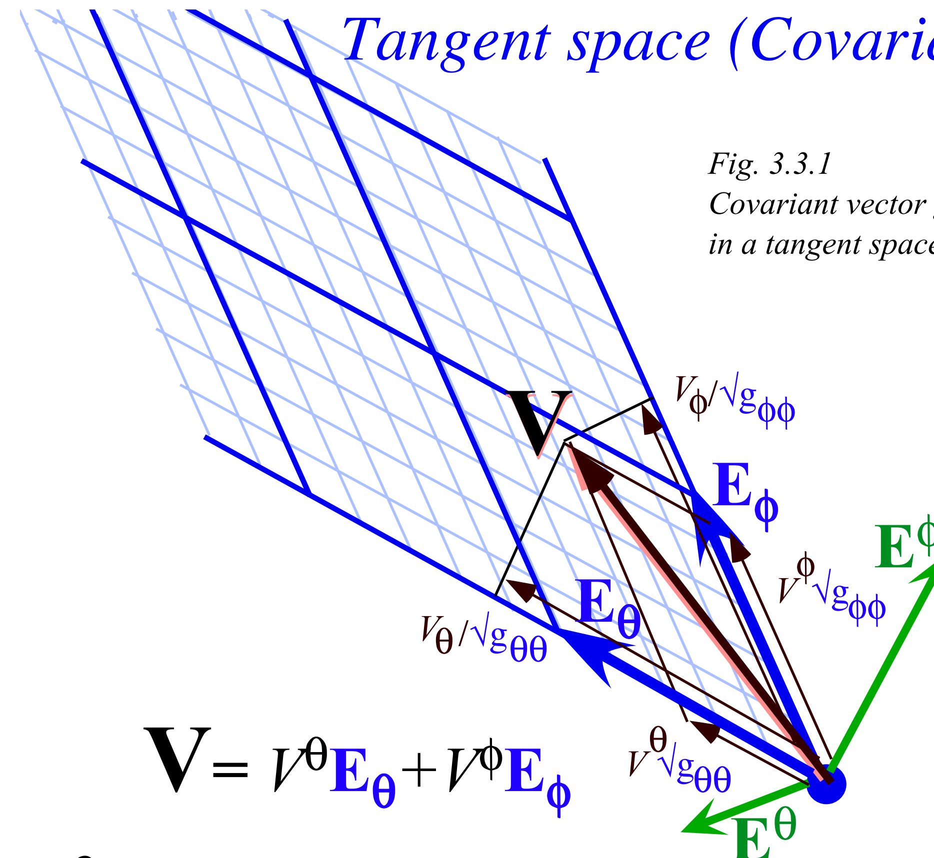


Fig. 3.3.1
Covariant vector geometry
in a tangent space ($\mathbf{E}_\theta, \mathbf{E}_\phi$ *).*

Contravariant vector $\mathbf{E^m}$ for frame $\{q^1, q^2, \cdots\}$ is written in terms of new vectors $\bar{\mathbf{E}}^{\bar{\mathbf{m}}}$ for a new "barred" frame $\{\bar{q}^1, \bar{q}^2, \cdots\}$ using a *"chain-saw-sum rule"....*

$$\mathbf{E^m} = \frac{\partial q^m}{\partial \mathbf{r}} = \frac{\partial q^m}{\qquad}\frac{}{\partial \mathbf{r}} = \frac{\partial q^m}{\partial \bar{q}^{\bar{m}}}\frac{\partial \bar{q}^{\bar{m}}}{\partial \mathbf{r}}, \quad \text{or:} \quad \boxed{\mathbf{E^m} = \frac{\partial q^m}{\partial \bar{q}^{\bar{m}}}\bar{\mathbf{E}}^{\bar{\mathbf{m}}}}$$

...and the same for covariant vectors $\mathbf{E_m}$ and $\bar{\mathbf{E}}_{\bar{\mathbf{m}}}$

$$\mathbf{E_m} = \frac{\partial \mathbf{r}}{\partial q^m} = \frac{}{\partial q^m}\frac{\partial \mathbf{r}}{\qquad} = \frac{\partial \bar{q}^{\bar{m}}}{\partial q^m}\frac{\partial \mathbf{r}}{\partial \bar{q}^{\bar{m}}}, \quad \text{or:} \quad \boxed{\mathbf{E_m} = \frac{\partial \bar{q}^{\bar{m}}}{\partial q^m}\bar{\mathbf{E}}_{\bar{\mathbf{m}}}}$$

Contravariant vectors $\mathbf{E}^m$ *versus* *Covariant vectors* $\mathbf{E}_n$

Any vector **U,V,...** is expressed using *either* set from any viewpoint, coordinate system, or *frame*,

$$\mathbf{U} = U^m\,\mathbf{E_m} = U_n\,\mathbf{E^n} = \bar{U}^{\bar{m}}\,\mathbf{\bar{E}_{\bar{m}}} = \bar{U}_{\bar{n}}\,\mathbf{\bar{E}^{\bar{n}}} \qquad \mathbf{V} = V^m\,\mathbf{E_m} = V_n\,\mathbf{E^n} = \bar{V}^{\bar{m}}\,\mathbf{\bar{E}_{\bar{m}}} = \bar{V}_{\bar{n}}\,\mathbf{\bar{E}^{\bar{n}}}$$

where the *Um, Vm,...are contravariant components* and the *Un , Vn ,...are covariant components*

$U^m = \mathbf{U} \bullet \mathbf{E^m}$, $V^m = \mathbf{V} \bullet \mathbf{E^m}$, and $\bar{U}^{\bar{m}} = \mathbf{U} \bullet \mathbf{\bar{E}^{\bar{m}}}$, $\bar{V}^{\bar{m}} = \mathbf{V} \bullet \mathbf{\bar{E}^{\bar{m}}}$, , $U_n = \mathbf{U} \bullet \mathbf{E_n}$, $V_n = \mathbf{V} \bullet \mathbf{E_n}$, and $\bar{U}_{\bar{n}} = \mathbf{U} \bullet \mathbf{\bar{E}_{\bar{n}}}$, *etc.*

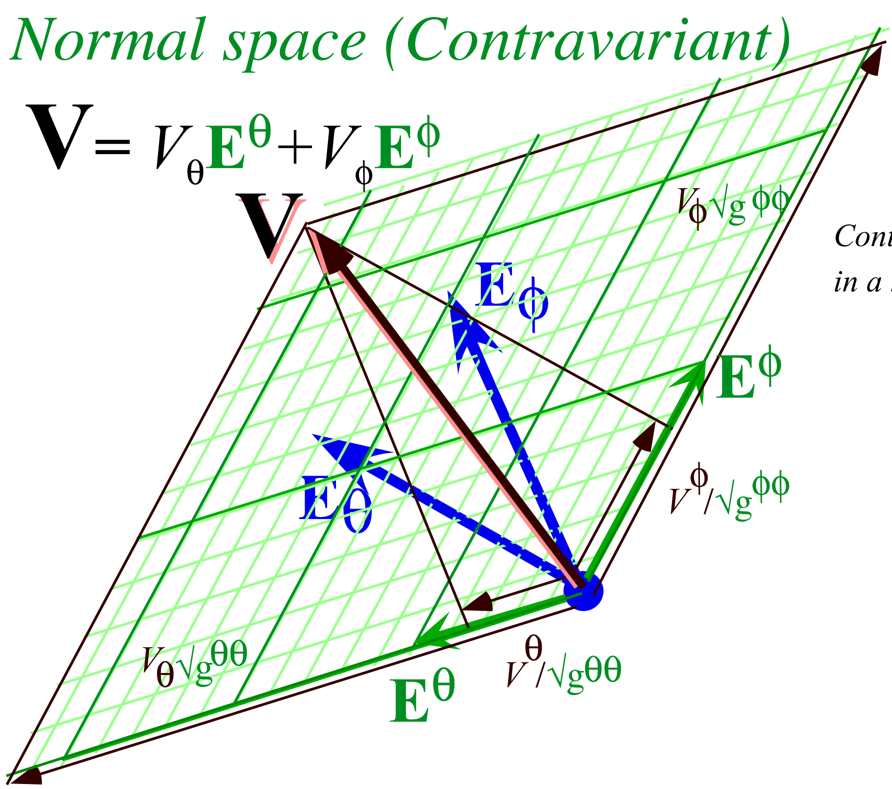


Fig. 3.3.2
Contravariant vector geometry in a normal space ($\mathbf{E}^\theta, \mathbf{E}^\phi$).

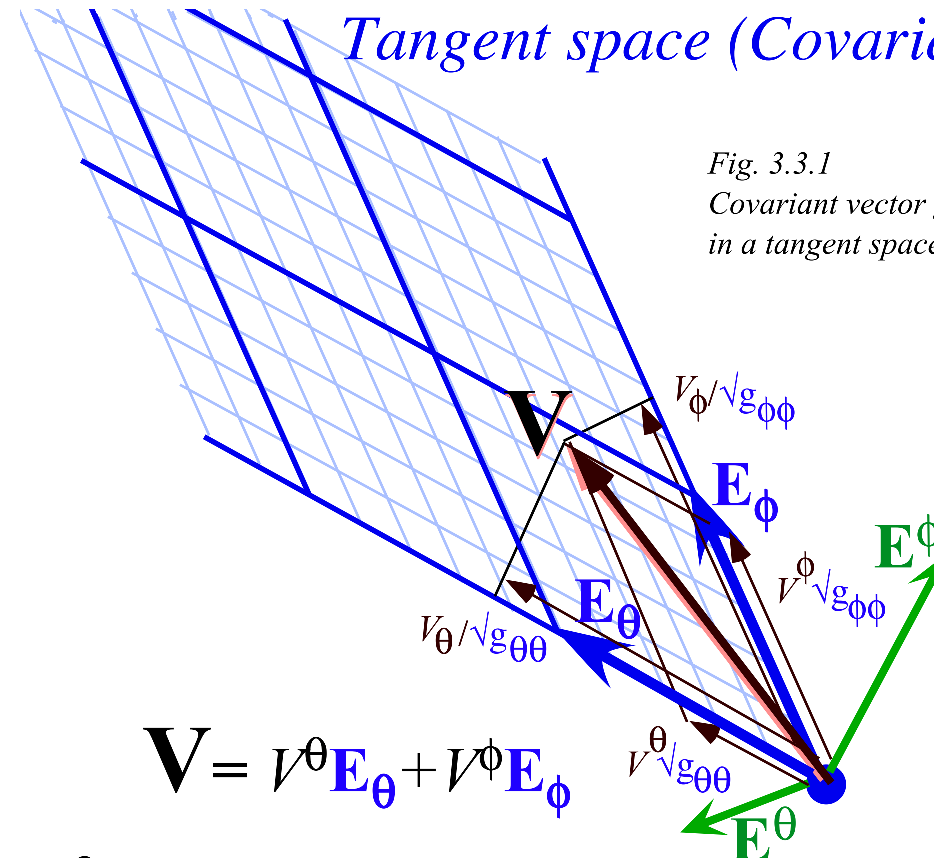


Fig. 3.3.1
Covariant vector geometry in a tangent space ($\mathbf{E}_\theta, \mathbf{E}_\phi$).

Contravariant vector $\mathbf{E^m}$ for frame $\{q^1, q^2, \cdots\}$ is written in terms of new vectors $\mathbf{\bar{E}^{\bar{m}}}$ for a new "barred" frame $\{\bar{q}^1, \bar{q}^2, \cdots\}$ using a *"chain-saw-sum rule"*….

...and the same for covariant vectors $\mathbf{E_m}$ and $\mathbf{\bar{E}_{\bar{m}}}$

$$\mathbf{E^m} = \frac{\partial q^m}{\partial \mathbf{r}} = \frac{\partial q^m}{}\frac{}{\partial \mathbf{r}} = \frac{\partial q^m}{\partial \bar{q}^{\bar{m}}}\frac{\partial \bar{q}^{\bar{m}}}{\partial \mathbf{r}}, \quad \text{or: } \boxed{\mathbf{E^m} = \frac{\partial q^m}{\partial \bar{q}^{\bar{m}}}\mathbf{\bar{E}^{\bar{m}}}}$$

implies: $V^m = \frac{\partial q^m}{\partial \bar{q}^{\bar{m}}}\bar{V}^{\bar{m}}$

$$\mathbf{E_m} = \frac{\partial \mathbf{r}}{\partial q^m} = \frac{}{\partial q^m}\frac{\partial \mathbf{r}}{} = \frac{\partial \bar{q}^{\bar{m}}}{\partial q^m}\frac{\partial \mathbf{r}}{\partial \bar{q}^{\bar{m}}}, \quad \text{or: } \boxed{\mathbf{E_m} = \frac{\partial \bar{q}^{\bar{m}}}{\partial q^m}\mathbf{\bar{E}_{\bar{m}}}}$$

implies: $V_m = \frac{\partial \bar{q}^{\bar{m}}}{\partial q^m}\bar{V}_{\bar{m}}$

Contravariant vectors $\mathbf{E}^m$ *versus* *Covariant vectors* $\mathbf{E}_n$

Any vector **U**,**V**,**...** is expressed using *either* set from any viewpoint, coordinate system, or *frame*,

$$\mathbf{U} = U^m\,\mathbf{E_m} = U_n\,\mathbf{E^n} = \bar{U}^{\bar{m}}\,\bar{\mathbf{E}}_{\bar{\mathbf{m}}} = \bar{U}_{\bar{n}}\,\bar{\mathbf{E}}^{\bar{\mathbf{n}}} \qquad \mathbf{V} = V^m\,\mathbf{E_m} = V_n\,\mathbf{E^n} = \bar{V}^{\bar{m}}\,\bar{\mathbf{E}}_{\bar{\mathbf{m}}} = \bar{V}_{\bar{n}}\,\bar{\mathbf{E}}^{\bar{\mathbf{n}}}$$

where the *Um, Vm,...are contravariant components*

$$U^m = \mathbf{U}\bullet\mathbf{E^m},\ V^m = \mathbf{V}\bullet\mathbf{E^m},\ \text{and}\ \bar{U}^{\bar{m}} = \mathbf{U}\bullet\bar{\mathbf{E}}^{\bar{\mathbf{m}}},\ \bar{V}^{\bar{m}} = \mathbf{V}\bullet\bar{\mathbf{E}}^{\bar{\mathbf{m}}},\,,$$

and the *Un , Vn ,...are covariant components*

$$U_n = \mathbf{U}\bullet\mathbf{E_n},\ V_n = \mathbf{V}\bullet\mathbf{E_n},\ \text{and}\ \bar{U}_{\bar{n}} = \mathbf{U}\bullet\bar{\mathbf{E}}_{\bar{\mathbf{n}}},\ etc.$$

Normal space (Contravariant)

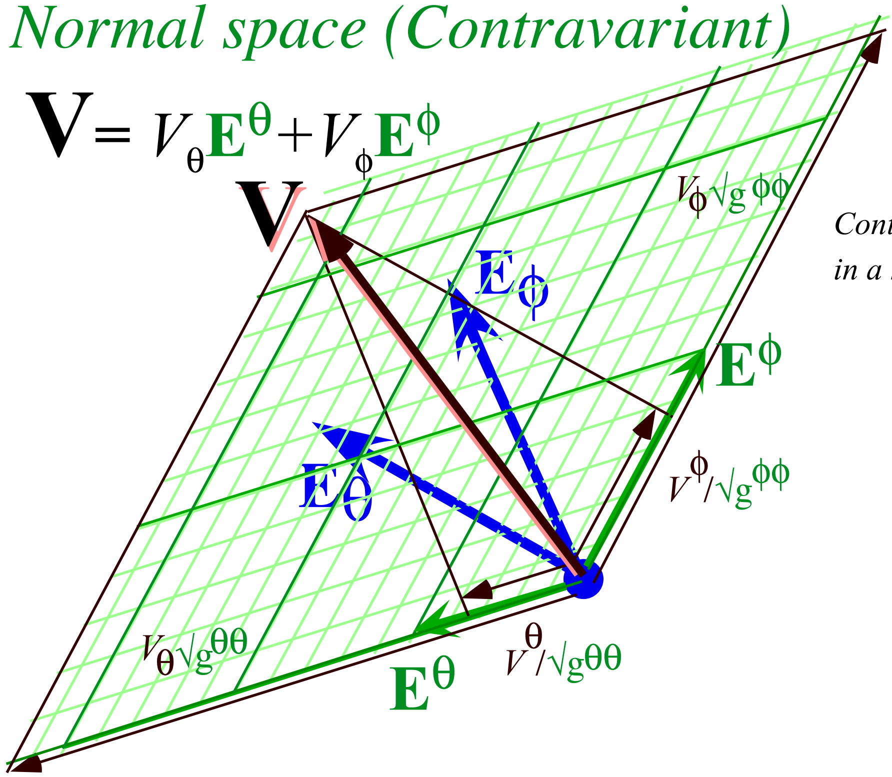


Fig. 3.3.2
Contravariant vector geometry
in a normal space ($\mathbf{E}^\theta,\mathbf{E}^\phi$).

Tangent space (Covariant)

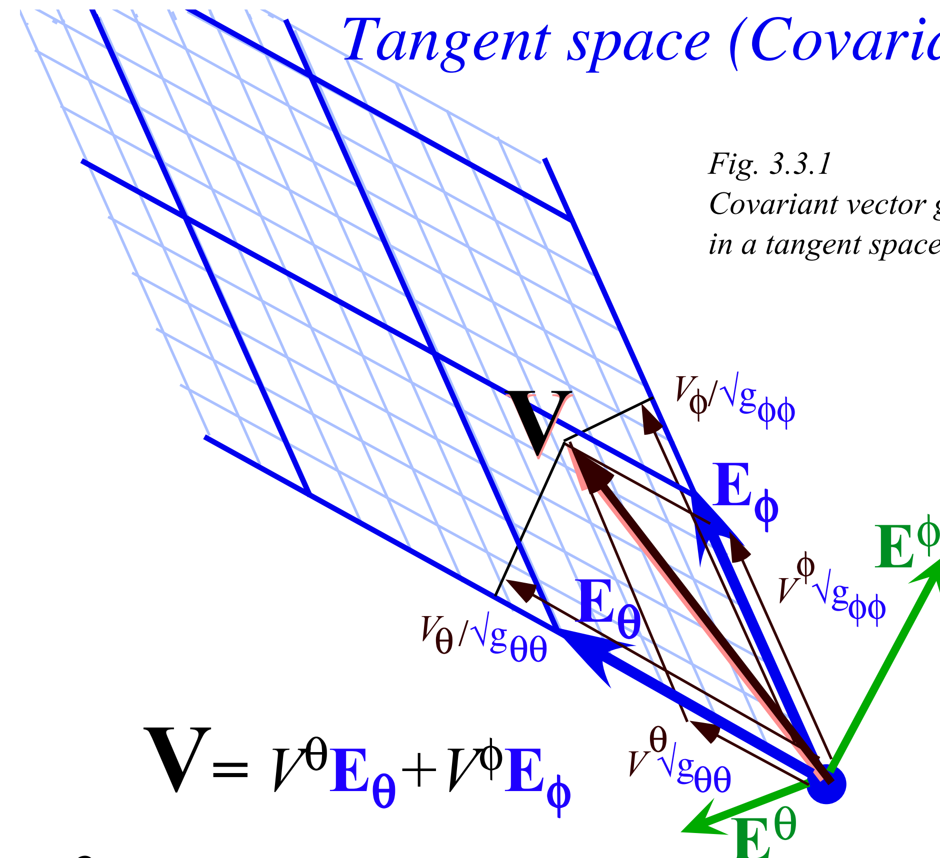


Fig. 3.3.1
Covariant vector geometry
in a tangent space ($\mathbf{E}_\theta,\mathbf{E}_\phi$).

Contravariant vector $\mathbf{E^m}$ for frame $\{q^1, q^2, \cdots\}$ is written in terms of new vectors $\bar{\mathbf{E}}^{\bar{\mathbf{m}}}$ for a new "barred" frame $\{\bar{q}^1, \bar{q}^2, \cdots\}$ using a *"chain-saw-sum rule"*....

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$$\mathbf{E_m} = \frac{\partial \mathbf{r}}{\partial q^m} = \frac{\quad}{\partial q^m}\frac{\partial \mathbf{r}}{} = \frac{\partial \bar{q}^{\bar{m}}}{\partial q^m}\frac{\partial \mathbf{r}}{\partial \bar{q}^{\bar{m}}}, \quad \text{or:} \quad \boxed{\mathbf{E_m} = \frac{\partial \bar{q}^{\bar{m}}}{\partial q^m}\bar{\mathbf{E}}_{\bar{\mathbf{m}}}}$$

Dirac notation equivalents:

$$\langle m| = \langle m|\cdot\mathbf{1} = \langle m|\cdot\sum_{\bar{m}}|\bar{m}\rangle\langle\bar{m}| = \sum_{\bar{m}}\langle m|\bar{m}\rangle\langle\bar{m}| \quad \text{implies:}\ \langle m|\Psi\rangle = \sum_{\bar{m}}\langle m|\bar{m}\rangle\langle\bar{m}|\Psi\rangle$$

Dirac notation equivalents:

$$|m\rangle = \mathbf{1}\cdot|m\rangle = \sum_{\bar{m}}|\bar{m}\rangle\langle\bar{m}||m\rangle = \sum_{\bar{m}}\langle\bar{m}|m\rangle|\bar{m}\rangle$$

Geometric and topological properties of GCC transformations (Mostly Unit 3.)

Multivalued functionality and connections

Covariant and contravariant relations

→ *Metric tensors*

Metric tensor **g** *covariant (and contravariant) metric components* g_{mn} *(and* g^{mn} *)*

$$g_{mn} = \mathbf{E_m} \bullet \mathbf{E_n} = g_{nm} \ , \quad g^{mn} = \mathbf{E^m} \bullet \mathbf{E^n} = g^{nm} \ .$$

Metric tensor **g** *covariant (and contravariant) metric components g_{mn} (and g^{mn})*

$$g_{mn} = \mathbf{E_m} \bullet \mathbf{E_n} = g_{nm} \;, \quad g^{mn} = \mathbf{E^m} \bullet \mathbf{E^n} = g^{nm} \;.$$

"Mixed" covariant-contravariant metric components

$$g_m^n = \mathbf{E_m} \bullet \mathbf{E^n} = g_m^n = \mathbf{E_m} \bullet \mathbf{E^n} = \delta_m^n = \begin{cases} 0 \text{ if: } m \neq n \\ 1 \text{ if: } m = n \end{cases}$$

Caution: δ_{mn} is g_{mn} and not δ_n^m in GCC.

Metric tensor **g** *covariant (and contravariant) metric components* g_{mn} *(and* g^{mn} *)*

$$g_{mn} = \mathbf{E_m} \bullet \mathbf{E_n} = g_{nm} \ , \quad g^{mn} = \mathbf{E^m} \bullet \mathbf{E^n} = g^{nm} \ .$$

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Metric coefficients express covariant unitary vectors in terms of contras and vice-versa

$$\mathbf{E_m} = g_{mn}\mathbf{E^n} \ , \qquad \mathbf{E^m} = g^{mn}\mathbf{E_n} \ .$$

Metric tensor **g** *covariant (and contravariant) metric components* g_{mn} *(and* g^{mn} *)*

$$g_{mn} = \mathbf{E_m} \bullet \mathbf{E_n} = g_{nm}\ , \quad g^{mn} = \mathbf{E^m} \bullet \mathbf{E^n} = g^{nm}\ .$$

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Metric coefficients express covariant unitary vectors in terms of contras and vice-versa

$$\mathbf{E_m} = g_{mn}\mathbf{E^n}\ , \qquad \mathbf{E^m} = g^{mn}\mathbf{E_n}\ .$$

Co-and-Contra vector and tensor components are related by g-transformation. (So are g's themselves.)

$$V_m = g_{mn}V^n, \qquad V^m = g^{mn}V_n\ , \quad T^{mm'} = g^{mn}g^{m'n'}V_{nn'}\ , \ etc.$$

Metric tensor **g** *covariant (and contravariant) metric components* g_{mn} *(and* g^{mn} *)*

$$g_{mn} = \mathbf{E_m} \bullet \mathbf{E_n} = g_{nm} , \quad g^{mn} = \mathbf{E^m} \bullet \mathbf{E^n} = g^{nm} .$$

"Mixed" covariant-contravariant metric components

$$g_m^n = \mathbf{E_m} \bullet \mathbf{E^n} = g_m^n = \mathbf{E_m} \bullet \mathbf{E^n} = \delta_m^n = \begin{cases} 0 & \text{if: } m \neq n \\ 1 & \text{if: } m = n \end{cases}$$

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Metric coefficients express covariant unitary vectors in terms of contras and vice-versa

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Co-and-Contra vector and tensor components are related by g-transformation. (So are g's themselves.)

$$V_m = g_{mn}V^n, \qquad V^m = g^{mn}V_n , \quad T^{mm'} = g^{mn}g^{m'n'}V_{nn'} , \ etc.$$

Diagonal square roots $\sqrt{g_{mm}}$ are the lengths of the covariant unitary vectors. $|\mathbf{E_m}| = \sqrt{\mathbf{E_m} \bullet \mathbf{E_m}} = \sqrt{g_{mm}}$

$$|\mathbf{E^m}| = \sqrt{\mathbf{E^m} \bullet \mathbf{E^m}} = \sqrt{g^{mm}}$$

tangent space area spanned by $V^1\mathbf{E}_1$ and $V^2\mathbf{E}_2$

$$Area\left(V^1 E_1, V^2 E_2\right) = V^1 V^2 \left|\mathbf{E_1} \times \mathbf{E_2}\right| = V^1 V^2 \sqrt{\left(\mathbf{E_1} \times \mathbf{E_2}\right) \bullet \left(\mathbf{E_1} \times \mathbf{E_2}\right)}$$

$$Area\left(V^1 E_1, V^2 E_2\right) = V^1 V^2 \sqrt{\left(\mathbf{E_1} \bullet \mathbf{E_1}\right)\left(\mathbf{E_2} \bullet \mathbf{E_2}\right) - \left(\mathbf{E_1} \bullet \mathbf{E_2}\right)\left(\mathbf{E_1} \bullet \mathbf{E_2}\right)}$$

$$= V^1 V^2 \sqrt{g_{11} g_{22} - g_{12} g_{12}} = V^1 V^2 \sqrt{\det \begin{vmatrix} g_{11} & g_{12} \\ g_{21} & g_{22} \end{vmatrix}}$$

3D Jacobian determinant *J*-columns are $\mathbf{E}_1$, $\mathbf{E}_2$ and $\mathbf{E}_3$.

$$Volume\left(V^1\mathbf{E}_1, V^2\mathbf{E}_2, V^3\mathbf{E}_3\right) = V^1 V^2 V^3 \left|\mathbf{E_1} \times \mathbf{E_2} \bullet \mathbf{E_3}\right| = V^1 V^2 V^3 \det \begin{vmatrix} \frac{\partial x^1}{\partial q^1} & \frac{\partial x^1}{\partial q^2} & \frac{\partial x^1}{\partial q^3} \\ \frac{\partial x^2}{\partial q^1} & \frac{\partial x^2}{\partial q^2} & \frac{\partial x^2}{\partial q^3} \\ \frac{\partial x^3}{\partial q^1} & \frac{\partial x^3}{\partial q^2} & \frac{\partial x^3}{\partial q^3} \end{vmatrix}$$

$$\begin{pmatrix} g_{11} & g_{12} & g_{13} \\ g_{21} & g_{22} & g_{23} \\ g_{31} & g_{32} & g_{33} \end{pmatrix} = \begin{pmatrix} \frac{\partial x^1}{\partial q^1} & \frac{\partial x^2}{\partial q^1} & \frac{\partial x^3}{\partial q^1} \\ \frac{\partial x^1}{\partial q^2} & \frac{\partial x^2}{\partial q^2} & \frac{\partial x^3}{\partial q^2} \\ \frac{\partial x^1}{\partial q^3} & \frac{\partial x^2}{\partial q^3} & \frac{\partial x^3}{\partial q^3} \end{pmatrix} \bullet \begin{pmatrix} \frac{\partial x^1}{\partial q^1} & \frac{\partial x^1}{\partial q^2} & \frac{\partial x^1}{\partial q^3} \\ \frac{\partial x^2}{\partial q^1} & \frac{\partial x^2}{\partial q^2} & \frac{\partial x^2}{\partial q^3} \\ \frac{\partial x^3}{\partial q^1} & \frac{\partial x^3}{\partial q^2} & \frac{\partial x^3}{\partial q^3} \end{pmatrix} = J^T \bullet J$$

Determinant product ($det|A|\ det|B| = det|A \bullet B|$) and symmetry ($det|A^T| = det|A|$) gives

$$Volume\left(V^1\mathbf{E}_1, V^2\mathbf{E}_2, V^3\mathbf{E}_3\right) = V^1 V^2 V^3 \det\left|J\right| = V^1 V^2 V^3 \sqrt{\det\left|g\right|}$$