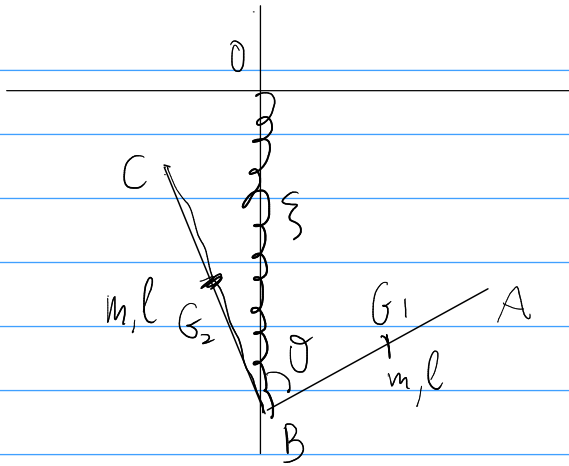


TE MA 07/02/25



$$(B-O) = (0, -\xi)$$

$$(G_1-B) = \left(\frac{l}{2} \sin \theta, \frac{l}{2} \cos \theta \right)$$

$$(G_2-B) = \left(-\frac{l}{2} \cos \theta, \frac{l}{2} \sin \theta \right)$$

$$\lambda = \frac{mg}{kl}$$

$$(G_1-O) = \left(\frac{l}{2} \sin \theta, -\xi + \frac{l}{2} \cos \theta \right)$$

$$(G_2-O) = \left(-\frac{l}{2} \cos \theta, -\xi + \frac{l}{2} \sin \theta \right)$$

$$|B-O|^2 = \xi^2$$

$$U = -mg \left(-\xi + \frac{l}{2} \cos \theta - \xi + \frac{l}{2} \sin \theta \right) - \frac{k}{2} \xi^2$$

$$= 2mg\xi - \frac{1}{2}mgl(\sin \theta + \cos \theta) - \frac{1}{2}k\xi^2$$

$$\frac{\partial U}{\partial \xi} = 2mg - k\xi = 0$$

$$\frac{\partial U}{\partial \theta} = -\frac{1}{2}mgl(\cos \theta - \sin \theta) = 0$$

$$\xi = \frac{2mg}{k}$$

$$\sin \vartheta = \cos \vartheta \quad \left\{ \begin{array}{l} \vartheta = \frac{\pi}{4} \\ \vartheta = \frac{3}{4}\pi \end{array} \right.$$

Stabilität:

$$H = \begin{bmatrix} -k & 0 \\ 0 & \frac{1}{2} m g l (\sin \vartheta + \cos \vartheta) \end{bmatrix}$$

$$H\left(\frac{2mg}{k}, \frac{\pi}{4}\right) = \begin{bmatrix} -k & 0 \\ 0 & \frac{\sqrt{2}}{2} m g l \end{bmatrix} \quad \text{INST}$$

$$H\left(\frac{2mg}{k}, \frac{3}{4}\pi\right) = \begin{bmatrix} -k & 0 \\ 0 & -\frac{\sqrt{2}}{2} m g l \end{bmatrix} \quad \text{STAB.}$$

$$K = \frac{1}{2} m v_{G_1}^2 + \frac{1}{2} m v_{G_2}^2 + \frac{1}{2} J_{33}^1 \dot{\vartheta}^2 + \frac{1}{2} J_{33}^2 \dot{\vartheta}^2$$

$$v_{G_1} = \left(\frac{l}{2} \dot{\vartheta} \cos \vartheta, -\dot{\xi} - \frac{l}{2} \dot{\vartheta} \sin \vartheta \right) \quad |v_{G_1}|^2 = \frac{l^2}{4} \dot{\vartheta}^2 + \dot{\xi}^2 + l \dot{\xi} \dot{\vartheta} \sin \vartheta$$

$$v_{G_2} = \left(\frac{l}{2} \dot{\vartheta} \sin \vartheta, -\dot{\xi} + \frac{l}{2} \dot{\vartheta} \cos \vartheta \right) \quad |v_{G_2}|^2 = \frac{l^2}{4} \dot{\vartheta}^2 + \dot{\xi}^2 - l \dot{\xi} \dot{\vartheta} \cos \vartheta$$

$$J_{33}^1 = J_{33}^2 = \frac{1}{12} m l^2$$

$$K = \frac{1}{2} m \left(\frac{e^2}{2} \dot{\vartheta}^2 + 2 \dot{\xi}^2 + l \dot{\xi} \dot{\vartheta} (\sin \vartheta - \cos \vartheta) \right) + \frac{1}{2} \frac{1}{6} m l^2 \dot{\vartheta}^2$$

$$K = \begin{bmatrix} 2m & \frac{e}{2} (\sin \vartheta - \cos \vartheta) \\ \frac{e}{2} (\sin \vartheta - \cos \vartheta) & \frac{2}{3} m l^2 \end{bmatrix}$$

$$P\left(\frac{2mg}{k}, \frac{3}{4}\pi\right) \quad H = \begin{bmatrix} -k & 0 \\ 0 & -\frac{\sqrt{2}}{2} m g l \end{bmatrix}$$

$$\tilde{\mathcal{L}} = \frac{1}{2} \dot{q} K \dot{q} + \frac{1}{2} (q - \bar{q}) H (q - \bar{q})$$

$$= \frac{1}{2} \begin{bmatrix} \dot{\xi} & \dot{\vartheta} \end{bmatrix} \begin{bmatrix} 2m & \frac{\sqrt{2}l}{4} \\ \frac{\sqrt{2}l}{4} & \frac{2}{3} m l^2 \end{bmatrix} \begin{bmatrix} \dot{\xi} \\ \dot{\vartheta} \end{bmatrix} + \frac{1}{2} \left[\xi - \frac{2mg}{k} \quad \vartheta - \frac{3}{4}\pi \right]$$

$$H \begin{bmatrix} \xi - \frac{2mg}{k} \\ \vartheta - \frac{3}{4}\pi \end{bmatrix}$$

□

$$\Pi \quad \begin{cases} Q = k q^\alpha e^{-P} \\ P = k q^\alpha e^P \end{cases} \quad \begin{matrix} k > 0 \\ 2e \in \mathbb{R} \end{matrix}$$

$$1 = [Q, P] = \cancel{k \alpha q^{\alpha-1} e^{-P} k q^\alpha e^P} + \cancel{k q^\alpha e^{-P} k \alpha q^{\alpha-1} e^P} = 2 k^2 \alpha q^{2\alpha-1} = 1$$

$$\Rightarrow 2\alpha = 1 \quad \alpha = \frac{1}{2} \quad \frac{k^2}{4} = 1 \quad k = 1$$

$$F_2(q, p)$$

$$\begin{cases} p = \frac{\partial F_2}{\partial q} \\ Q = \frac{\partial F_2}{\partial p} = \frac{q}{2p} \end{cases}$$

$$e^p = \frac{p}{kq^\alpha}$$

$$Q = \frac{kq^\alpha}{p} \quad kq^\alpha = \frac{q}{p} = \frac{q}{L}$$

$$e^p = \frac{L}{q^{1/2}}$$

$$p = \ln \left(\frac{L}{q^{1/2}} \right)$$

$$F_2 = q \ln L + g(q)$$

$$\frac{\partial F_2}{\partial q} = \cancel{\ln L} + g'(q) = \cancel{\ln L} - \ln(q^{1/2})$$

$$g'(q) = -\frac{1}{2} \ln q$$

$$g(q) = -\frac{1}{2} (q \ln q - q) + c = -\frac{1}{2} q \ln q + \frac{q}{2} + c$$

$$\Rightarrow F_2(q, p) = q \ln L - \frac{1}{2} q \ln q + \frac{q}{2} + c$$

$$= q \left(\ln \frac{L}{\sqrt{q}} + \frac{1}{2} \right) + c$$

□