

# CONTENTS

## CHAPTER I

### KINEMATICAL PRELIMINARIES

SECTION	PAGE
1. The displacements of rigid bodies . . . . .	1
2. Euler's theorem on rotations about a point . . . . .	2
3. The theorem of Rodrigues and Hamilton . . . . .	3
4. The composition of equal and opposite rotations about parallel axes . . . . .	3
5. Chasles' theorem on the most general displacement of a rigid body . . . . .	4
6. Halphen's theorem on the composition of two general displacements . . . . .	5
7. Analytic representation of a displacement . . . . .	6
8. The composition of small rotations . . . . .	7
9. Euler's parametric specification of rotations round a point . . . . .	8
10. The Eulerian angles . . . . .	9
11. Connexion of the Eulerian angles with the parameters $\xi, \eta, \zeta, \chi$ . . . . .	10
12. The connexion of rotations with homographies: the Cayley-Klein parameters . . . . .	11
13. Vectors . . . . .	13
14. Velocity and acceleration ; their vectorial character . . . . .	14
15. Angular velocity ; its vectorial character . . . . .	15
16. Determination of the components of angular velocity of a system in terms of the Eulerian angles, and of the symmetrical parameters . . . . .	16
17. Time-flux of a vector whose components relative to moving axes are given . . . . .	17
18. Special resolutions of the velocity and acceleration . . . . .	18
MISCELLANEOUS EXAMPLES . . . . .	22

## CHAPTER II

### THE EQUATIONS OF MOTION

19. The ideas of rest and motion . . . . .	26
20. The laws which determine motion . . . . .	27
21. Force . . . . .	29
22. Work . . . . .	30
23. Forces which do no work . . . . .	31
24. The coordinates of a dynamical system . . . . .	32
25. Holonomic and non-holonomic systems . . . . .	33

SECTION	PAGE
26. Lagrange's form of the equations of motion of a holonomic system . . . . .	34
27. Conservative forces; the kinetic potential . . . . .	38
28. The explicit form of Lagrange's equations . . . . .	39
29. Motion of a system which is constrained to rotate uniformly round an axis . . . . .	40
30. The Lagrangian equations for quasi-coordinates . . . . .	41
31. Forces derivable from a potential-function which involves the velocities . . . . .	44
32. Initial motions . . . . .	45
33. Similarity in dynamical systems . . . . .	47
34. Motion with reversed forces . . . . .	47
35. Impulsive motion . . . . .	48
36. The Lagrangian equations of impulsive motion . . . . .	50
MISCELLANEOUS EXAMPLES . . . . .	51

### CHAPTER III

#### PRINCIPLES AVAILABLE FOR THE INTEGRATION

37. Problems which are soluble by quadratures . . . . .	52
38. Systems with ignorable coordinates . . . . .	54
39. Special cases of ignoration; integrals of momentum and angular momentum . . . . .	58
40. The general theorem of angular momentum . . . . .	61
41. The energy equation . . . . .	62
42. Reduction of a dynamical problem to a problem with fewer degrees of freedom, by means of the energy equation . . . . .	64
43. Separation of the variables; dynamical systems of Liouville's type . . . . .	67
MISCELLANEOUS EXAMPLES . . . . .	69

### CHAPTER IV

#### THE SOLUBLE PROBLEMS OF PARTICLE DYNAMICS

44. The particle with one degree of freedom; the pendulum . . . . .	71
45. Motion in a moving tube . . . . .	74
46. Motion of two interacting free particles . . . . .	76
47. Central forces in general: Hamilton's theorem . . . . .	77
48. The integrable cases of central forces; problems soluble in terms of circular and elliptic functions . . . . .	80
49. Motion under the Newtonian law . . . . .	86
50. The mutual transformation of fields of central force and fields of parallel force . . . . .	93
51. Bonnet's theorem . . . . .	94
52. Determination of the most general field of force under which a given curve or family of curves can be described . . . . .	95
53. The problem of two centres of gravitation . . . . .	97
54. Motion on a surface . . . . .	99
55. Motion on a surface of revolution; cases soluble in terms of circular and elliptic functions . . . . .	103
56. Joukovsky's theorem . . . . .	109
MISCELLANEOUS EXAMPLES . . . . .	111

CHAPTER V

THE DYNAMICAL SPECIFICATION OF BODIES

SECTION	PAGE
57. Definitions . . . . .	117
58. The moments of inertia of some simple bodies . . . . .	118
59. Derivation of the moment of inertia about any axis when the moment of inertia about a parallel axis through the centre of gravity is known . . . . .	121
60. Connexion between moments of inertia with respect to different sets of axes through the same origin . . . . .	122
61. The principal axes of inertia; Cauchy's momental ellipsoid . . . . .	124
62. Calculation of the angular momentum of a moving rigid body . . . . .	124
63. Calculation of the kinetic energy of a moving rigid body . . . . .	126
64. Independence of the motion of the centre of gravity and the motion relative to it . . . . .	127
MISCELLANEOUS EXAMPLES . . . . .	129

CHAPTER VI

THE SOLUBLE PROBLEMS OF RIGID DYNAMICS

65. The motion of systems with one degree of freedom; motion round a fixed axis, etc. . . . .	131
66. The motion of systems with two degrees of freedom . . . . .	137
67. Initial motions . . . . .	141
68. The motion of systems with three degrees of freedom . . . . .	143
69. Motion of a body about a fixed point under no forces . . . . .	144
70. Poincot's kinematical representation of the motion; the polhode and herpolhode . . . . .	152
71. Motion of a top on a perfectly rough plane; determination of the Eulerian angle $\theta$ . . . . .	155
72. Determination of the remaining Eulerian angles, and of the Cayley-Klein parameters; the spherical top . . . . .	159
73. Motion of a top on a perfectly smooth plane . . . . .	163
74. Kowalevski's top . . . . .	164
75. Impulsive motion . . . . .	167
MISCELLANEOUS EXAMPLES . . . . .	169

CHAPTER VII

THEORY OF VIBRATIONS

76. Vibrations about equilibrium . . . . .	177
77. Normal coordinates . . . . .	178
78. Sylvester's theorem on the reality of the roots of the determinantal equation . . . . .	183
79. Solution of the differential equations; the periods; stability . . . . .	185
80. Examples of vibrations about equilibrium . . . . .	187
81. Effect of a new constraint on the periods of a vibrating system . . . . .	191
82. The stationary character of normal vibrations . . . . .	192
83. Vibrations about steady motion . . . . .	193
84. The integration of the equations . . . . .	195
85. Examples of vibrations about steady motion . . . . .	203
86. Vibrations of systems involving moving constraints . . . . .	207
MISCELLANEOUS EXAMPLES . . . . .	208

## CHAPTER VIII

## NON-HOLONOMIC SYSTEMS, DISSIPATIVE SYSTEMS

SECTION	PAGE
87. Lagrange's equations with undetermined multipliers . . . . .	214
88. Equations of motion referred to axes moving in any manner . . . . .	216
89. Application to special non-holonomic problems . . . . .	217
90. Vibrations of non-holonomic systems . . . . .	221
91. Dissipative systems; frictional forces . . . . .	226
92. Resisting forces which depend on the velocity . . . . .	229
93. Rayleigh's dissipation-function . . . . .	230
94. Vibrations of dissipative systems . . . . .	232
95. Impact . . . . .	234
96. Loss of kinetic energy in impact . . . . .	234
97. Examples of impact . . . . .	235
MISCELLANEOUS EXAMPLES . . . . .	238

## CHAPTER IX

## THE PRINCIPLES OF LEAST ACTION AND LEAST CURVATURE

98. The trajectories of a dynamical system . . . . .	245
99. Hamilton's principle for conservative holonomic systems . . . . .	245
100. The principle of Least Action for conservative holonomic systems . . . . .	247
101. Extension of Hamilton's principle to non-conservative dynamical systems . . . . .	248
102. Extension of Hamilton's principle and the principle of Least Action to non-holonomic systems . . . . .	249
103. Are the stationary integrals actual minima? Kinetic foci . . . . .	250
104. Representation of the motion of dynamical systems by means of geodesics . . . . .	253
105. The least-curvature principle of Gauss and Hertz . . . . .	254
106. Expression of the curvature of a path in terms of generalised coordinates . . . . .	256
107. Appell's equations . . . . .	258
108. Bertrand's theorem . . . . .	260
MISCELLANEOUS EXAMPLES . . . . .	261

## CHAPTER X

## HAMILTONIAN SYSTEMS AND THEIR INTEGRAL-INVARIANTS

109. Hamilton's form of the equations of motion . . . . .	263
110. Equations arising from the Calculus of Variations . . . . .	265
111. Integral-invariants . . . . .	267
112. The variational equations . . . . .	268
113. Integral-invariants of order one . . . . .	269
114. Relative integral-invariants . . . . .	271
115. A relative integral-invariant which is possessed by all Hamiltonian systems . . . . .	272
116. On systems which possess the relative integral-invariant $\int \Sigma p \delta q$ . . . . .	272
117. The expression of integral-invariants in terms of integrals . . . . .	274
118. The theorem of Lie and Koenigs . . . . .	275
119. The last multiplier . . . . .	276

SECTION	PAGE
120. Derivation of an integral from two multipliers . . . . .	279
121. Application of the last multiplier to Hamiltonian systems; use of a single known integral . . . . .	280
122. Integral-invariants whose order is equal to the order of the system . . . . .	283
123. Reduction of differential equations to the Lagrangian form . . . . .	284
124. Case in which the kinetic energy is quadratic in the velocities . . . . .	285
MISCELLANEOUS EXAMPLES . . . . .	286

## CHAPTER XI

### THE TRANSFORMATION-THEORY OF DYNAMICS

125. Hamilton's Characteristic Function and contact-transformations . . . . .	288
126. Contact-transformations in space of any number of dimensions . . . . .	292
127. The bilinear covariant of a general differential form . . . . .	296
128. The conditions for a contact-transformation expressed by means of the bilinear covariant . . . . .	297
129. The conditions for a contact-transformation in terms of Lagrange's bracket-expressions . . . . .	298
130. Poisson's bracket-expressions . . . . .	299
131. The conditions for a contact-transformation expressed by means of Poisson's bracket-expressions . . . . .	300
132. The sub-groups of Mathieu transformations and extended point-transformations . . . . .	301
133. Infinitesimal contact-transformations . . . . .	302
134. The resulting new view of dynamics . . . . .	304
135. Helmholtz's reciprocal theorem . . . . .	304
136. Jacobi's theorem on the transformation of a given dynamical system into another dynamical system . . . . .	305
137. Representation of a dynamical problem by a differential form . . . . .	307
138. The Hamiltonian function of the transformed equations . . . . .	309
139. Transformations in which the independent variable is changed . . . . .	310
140. New formulation of the integration-problem . . . . .	310
MISCELLANEOUS EXAMPLES . . . . .	311

## CHAPTER XII

### PROPERTIES OF THE INTEGRALS OF DYNAMICAL SYSTEMS

141. Reduction of the order of a Hamiltonian system by use of the energy integral . . . . .	313
142. Hamilton's partial differential equation . . . . .	314
143. Hamilton's integral as a solution of Hamilton's partial differential equation . . . . .	316
144. The connexion of integrals with infinitesimal transformations admitted by the system . . . . .	318
145. Poisson's theorem . . . . .	320
146. The constancy of Lagrange's bracket-expressions . . . . .	321
147. Involution-systems . . . . .	322

SECTION	PAGE
148. Solution of a dynamical problem when half the integrals are known . . . . .	323
149. Levi-Civita's theorem . . . . .	325
150. Systems which possess integrals linear in the momenta . . . . .	328
151. Determination of the forces acting on a system for which an integral is known . . . . .	331
152. Application to the case of a particle whose equations of motion possess an integral quadratic in the velocities . . . . .	332
153. General dynamical systems possessing integrals quadratic in the velocities . . . . .	335
MISCELLANEOUS EXAMPLES . . . . .	336

## CHAPTER XIII

### THE REDUCTION OF THE PROBLEM OF THREE BODIES

154. Introduction . . . . .	339
155. The differential equations of the problem . . . . .	340
156. Jacobi's equation . . . . .	342
157. Reduction to the 12th order, by use of the integrals of motion of the centre of gravity . . . . .	343
158. Reduction to the 8th order, by use of the integrals of angular momentum and elimination of the nodes . . . . .	344
159. Reduction to the 6th order . . . . .	347
160. Alternative reduction of the problem from the 18th to the 6th order . . . . .	348
161. The problem of three bodies in a plane . . . . .	351
162. The restricted problem of three bodies . . . . .	353
163. Extension to the problem of $n$ bodies . . . . .	356
MISCELLANEOUS EXAMPLES . . . . .	356

## CHAPTER XIV

### THE THEOREMS OF BRUNS AND POINCARÉ

164. Bruns' theorem	
(i) Statement of the theorem . . . . .	358
(ii) Expression of an integral in terms of the essential coordinates of the problem . . . . .	358
(iii) An integral must involve the momenta . . . . .	359
(iv) Only one irrationality can occur in the integral . . . . .	360
(v) Expression of the integral as a quotient of two real polynomials . . . . .	361
(vi) Derivation of integrals from the numerator and denominator of the quotient . . . . .	362
(vii) Proof that $\phi_0$ does not involve the irrationality . . . . .	366
(viii) Proof that $\phi_0$ is a function only of the momenta and the integrals of angular momentum . . . . .	371
(ix) Proof that $\phi_0$ is a function of $T, L, M, N$ . . . . .	374
(x) Deduction of Bruns' theorem, for integrals which do not involve $t$ . . . . .	376
(xi) Extension of Bruns' result to integrals which involve the time . . . . .	378

SECTION	PAGE
<b>165. Poincaré's theorem</b>	
(i) The equations of motion of the restricted problem of three bodies . . . . .	380
(ii) Statement of Poincaré's theorem . . . . .	381
(iii) Proof that $\Phi_0$ is not a function of $H_0$ . . . . .	381
(iv) Proof that $\Phi_0$ cannot involve the variables $q_1, q_2$ . . . . .	382
(v) Proof that the existence of a one-valued integral is inconsistent with the result of (iii) in the general case . . . . .	383
(vi) Removal of the restrictions on the coefficients $B_{m_1, m_2}$ . . . . .	384
(vii) Deduction of Poincaré's theorem . . . . .	385

## CHAPTER XV

### THE GENERAL THEORY OF ORBITS

<b>166. Introduction</b> . . . . .	386
<b>167. Periodic solutions</b> . . . . .	386
<b>168. A criterion for the discovery of periodic orbits</b> . . . . .	386
<b>169. Asymptotic solutions</b> . . . . .	389
<b>170. The orbits of planets in the relativity-theory</b> . . . . .	389
<b>171. The motion of a particle on an ellipsoid under no external forces</b> . . . . .	393
<b>172. Ordinary and singular periodic solutions</b> . . . . .	395
<b>173. Characteristic exponents</b> . . . . .	397
<b>174. Characteristic exponents when <math>t</math> does not occur explicitly</b> . . . . .	398
<b>175. The characteristic exponents of a system which possesses a one-valued integral</b>	399
<b>176. The theory of matrices</b> . . . . .	400
<b>177. The characteristic exponents of a Hamiltonian system</b> . . . . .	402
<b>178. The asymptotic solutions of § 170 deduced from the theory of characteristic     exponents</b> . . . . .	405
<b>179. The characteristic exponents of "ordinary" and "singular" periodic solutions</b>	406
<b>180. Lagrange's three particles</b> . . . . .	406
<b>181. Stability of Lagrange's particles: periodic orbits in the vicinity</b> . . . . .	409
<b>182. The stability of orbits as affected by terms of higher order in the displacement</b>	412
<b>183. Attractive and repellent regions of a field of force</b> . . . . .	413
<b>184. Application of the energy integral to the problem of stability</b> . . . . .	416
<b>185. Application of integral-invariants to investigations of stability</b> . . . . .	417
<b>186. Syngé's "Geometry of Dynamics"</b> . . . . .	417
<b>187. Connexion with the theory of surface transformations</b> . . . . .	420
<b>MISCELLANEOUS EXAMPLES</b> . . . . .	420

## CHAPTER XVI

### INTEGRATION BY SERIES

<b>188. The need for series which converge for all values of the time; Poincaré's     series</b> . . . . .	423
<b>189. The regularisation of the problem of three bodies</b> . . . . .	424
<b>190. Trigonometric series</b> . . . . .	425
<b>191. Removal of terms of the first degree from the energy function</b> . . . . .	426

SECTION	PAGE
192. Determination of the normal coordinates by a contact-transformation . . . . .	427
193. Transformation to the trigonometric form of $H$ . . . . .	430
194. Other types of motion which lead to equations of the same form . . . . .	431
195. The problem of integration . . . . .	432
196. Determination of the adelphic integral in Case I . . . . .	433
197. An example of the adelphic integral in Case I . . . . .	436
198. The question of convergence . . . . .	437
199. Use of the adelphic integral in order to complete the integration . . . . .	438
200. The fundamental property of the adelphic integral . . . . .	442
201. Determination of the adelphic integral in Case II . . . . .	443
202. An example of the adelphic integral in Case II . . . . .	444
203. Determination of the adelphic integral in Case III . . . . .	446
204. An example of the adelphic integral in Case III . . . . .	447
205. Completion of the integration of the dynamical system in Cases II and III . . . . .	449
MISCELLANEOUS EXAMPLES . . . . .	449
INDEX OF AUTHORS QUOTED . . . . .	451
INDEX OF TERMS EMPLOYED . . . . .	453