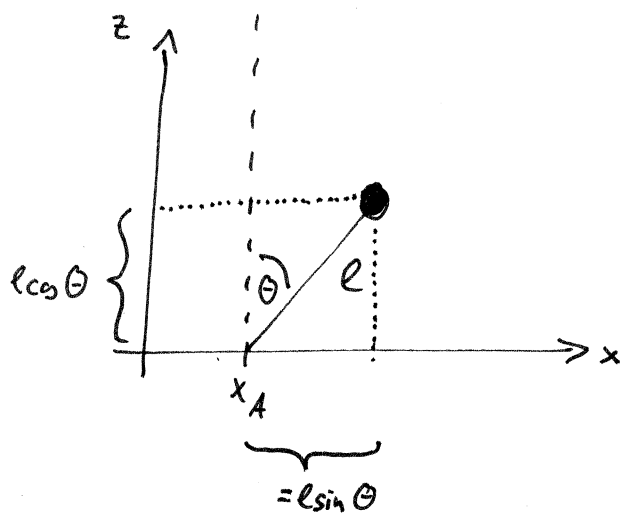


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$$x = x_A + l \sin \theta$$

$$z = + l \cos \theta$$

$$a) \quad \dot{x} = \dot{x}_A + l \cos \theta \dot{\theta}, \quad \dot{z} = -l \sin \theta \dot{\theta}, \quad j = \frac{\dot{x}_A}{e}, \quad \dot{j} = \frac{\dot{x}_A}{e}, \quad \lambda = \sqrt{\frac{g}{e}}$$

$$\begin{aligned} T &= \frac{m}{2} (\dot{x}^2 + \dot{z}^2) = \frac{m}{2} \left(\dot{x}_A^2 + 2l \dot{x}_A \dot{\theta} \cos \theta + l^2 \cos^2 \theta \dot{\theta}^2 + l^2 \sin^2 \theta \dot{\theta}^2 \right) \\ &= \frac{m}{2} \left(\dot{x}_A^2 + 2l \cos \theta \dot{x}_A \dot{\theta} + l^2 \dot{\theta}^2 \right) = \frac{m e^2}{2} \left(\frac{\dot{x}_A^2}{e^2} + 2 \cos \theta \frac{\dot{x}_A}{e} \dot{\theta} + \dot{\theta}^2 \right) \\ &= \frac{m e^2}{2} \left(\dot{\theta}^2 + 2 \dot{j} \dot{\theta} \cos \theta + \dot{j}^2 \right) \end{aligned}$$

$$V = mgz = mg l \cos \theta$$

Lagrange-Funktion:

$$\mathcal{L} = T - V = \frac{m e^2}{2} \left(\dot{\theta}^2 + 2 \dot{j} \dot{\theta} \cos \theta + \dot{j}^2 \right) - mg l \cos \theta$$

Bewegungsgleichungen:

$$0 = \frac{d}{dt} \frac{\partial \mathcal{L}}{\partial \dot{\theta}} - \frac{\partial \mathcal{L}}{\partial \theta} = \frac{d}{dt} \left(m e^2 \dot{\theta} + m e^2 \dot{j} \cos \theta \right) - \left(+ mg l \sin \theta - m e^2 \dot{j} \dot{\theta} \sin \theta \right)$$

$$= m e^2 \ddot{\theta} + m e^2 \dot{j} \cos \theta - \underline{m e^2 \dot{j} \dot{\theta} \sin \theta} - mg l \sin \theta + \underline{m e^2 \dot{j} \dot{\theta} \sin \theta}$$

$$= m e^2 \ddot{\theta} + m e^2 \dot{j} \cos \theta - mg l \sin \theta$$

$$\Leftrightarrow \ddot{\theta} + \dot{j} \cos \theta - \lambda^2 \sin \theta = 0$$

b) $|\Theta| \ll 1$, $\sin \Theta \approx \Theta$, $\cos \Theta \approx 1$

$$\Rightarrow \ddot{\Theta} + \dot{j} - \lambda^2 \Theta = 0$$

$$\ddot{\Theta} - \lambda^2 \Theta = -\dot{j}$$

c) Ansatz: $\Theta(t) = A e^{\mu t}$

$$A \mu^2 e^{\mu t} - \lambda^2 A e^{\mu t} = 0$$

$$\mu^2 = \lambda^2$$

$$\mu = \pm \lambda \Rightarrow \Theta^{(0)}(t) = \alpha e^{\lambda t} + \beta e^{-\lambda t}$$

2 Integrationskonstanten, da 2 AB, da DGL 2. Ordnung.

d) $f(t) = f_0 \sin \omega t$, $\ddot{j}(t) = -f_0 \omega^2 \sin \omega t$

$$\Theta^{(1)}(t) = \Theta_0 \sin \omega t$$

Einsetzen von f , $\Theta^{(1)}$ in DGL $\ddot{\Theta} - \lambda^2 \Theta = -\dot{j}$:

$$-\Theta_0 \omega^2 \sin \omega t + \lambda^2 \Theta_0 \sin \omega t = f_0 \omega^2 \sin \omega t$$

$$\Theta_0 = -\frac{f_0 \omega^2}{\omega^2 + \lambda^2}$$

e) $\Theta(t) = \alpha e^{\lambda t} + \beta e^{-\lambda t} + \Theta_0 \sin \omega t$

Lösung beschränkt $\Leftrightarrow |\Theta(t \rightarrow \infty)| < \infty$

Da $\lambda = \sqrt{\frac{3}{e}} > 0$, muss gelten: $\alpha = 0$ (sonst ist die Lsg nicht beschränkt)

$$\Rightarrow \Theta(t) = \beta e^{-\lambda t} + \Theta_0 \sin \omega t$$

$$\Theta(0) = \beta$$

$$\dot{\Theta}(0) = -\lambda \beta - \Theta_0 \omega = -\lambda \Theta(0) - \Theta_0 \omega$$