1.0 INTRODUCTION

This paper is intended as a minimal introduction to the application of Lagrange equations to the task of finding the equations of motion of a system of rigid bodies. A much more thorough and rigorous treatment is given in the text “Fundamentals of Applied Dynamics” by Prof. James H. Williams, Jr., published in 1996 by John Wiley and Sons. In particular the treatment given here to the evaluation of non-conservative external forces is simple and pragmatic. It will suffice for most of the applications at the level of an undergraduate course in engineering dynamics. Deeper understanding requires more work and the reader is referred to the Williams text. In writing this summary I have borrowed liberally from the Williams text and also from a previous subject handout, prepared by Prof. Sanjay Sarma of the Mechanical Engineering Department of MIT.

2.0 ENERGY METHODS IN STATICS

Principle of virtual work: Energy methods were in use to solve statics problems before discovering them for dynamics. One example is the principle of virtual work. If a structure such as the one shown in the diagram below is in static equilibrium then from the principle of virtual work we can deduce the static equilibrium equation by computing the virtual work done during an infinitesimal deflection. In this case the uniform bar, shown in Figure 1, rotates about the hinge at A.

It is acted upon by its weight, Mg, applied at its center of gravity at B, a spring force, Fs, applied at its point of attachment at C, and by the workless constraint reaction force, Ry, applied at A. Assume the static equilibrium position is horizontal and assume a small virtual angular displacement, $\delta\theta$. The principal of virtual work tells us that the work done by all of the forces in the course of the virtual displacement is zero. Putting this into equation form yields directly the relationship between the applied external gravitational force and the internal spring force as shown below.
\[ \delta W = [R_y \bullet 0 - Mg \delta y_1 + F_s \delta y_2] = 0 \]

Noting that \( \delta y_1 = \frac{L}{2} \delta \theta \) and \( \delta y_2 = L \delta \theta \), then
\[ [-Mg \frac{L}{2} + F_s L] \delta \theta = 0 \]

Since \( \delta \phi \neq 0 \), then the part inside the brackets must equal zero.
\[ [-Mg \frac{L}{2} + F_s L] = 0, \text{ the condition for static equilibrium.} \] (2.1)

Solving for the unknown spring force yields
\[ F_{spring} = \frac{Mg}{2} \]

An important feature to note is that \( R_y \), the reaction force at the hinge does not appear in the final expression, because it does no work during the virtual displacement. This is a benefit that carries over to dynamical systems when the concept of virtual work is extended to application of Lagrange equations to problems in dynamics. The equations of motion can be found without having to solve for workless constraint forces.

Principle of minimum potential energy: Another related concept came into use for the analysis of elastic structures for which it was possible to evaluate the total potential energy of the system, including strain energy stored in structural elements and strain energy due to gravitational loads. This can be illustrated by considering a simple weight hanging on a spring, as shown in Figure 2. This is a system in which only one coordinate, \( x \) is needed to describe the vertical deflection of the system.
As shown in the diagram, the origin is taken to be at the position where the spring force is zero. The deflection, $x$, is positive downwards. The total potential energy of the system for a positive deflection of the mass may be expressed as:

$$V = -\int F \cdot dx = \frac{1}{2} Kx^2 - Mg$$  \hspace{1cm} (2.2)$$

The principle of minimum potential energy states that “Of all the states which satisfy the boundary conditions(constraints), the correct state is that which makes the total potential energy minimum.” Mathematically this can be expressed as:

$$\frac{\partial V}{\partial x} = kx - Mg = 0$$

$$\Rightarrow x = \frac{Mg}{k}$$  \hspace{1cm} (2.3)$$

Thus, from knowing the total potential energy of the system, and by applying this principle, one may directly obtain the static equilibrium equation as well as the deflection, $x$, as a function of the applied load, $Mg$.

There is a very useful conceptual link between the principle of virtual work and the principle of minimum potential energy. If we imagine a small virtual deflection of the system about its static equilibrium position then we can modify the equations obtained above to define the variation in the potential energy in terms of the virtual work, which results from a small virtual displacement, $\delta x$, as shown below. The two expressions on the left hand side represent the variation in the potential energy whereas the expression on the right hand side shows the virtual work. Both are equal to zero because this is a small variation about a static equilibrium position for a system with no non-conservative forces acting on it.
\[
\delta V = \frac{\partial V}{\partial x} \delta x = (kx - Mg) \delta x = 0
\] (2.4)

In fact the term \(\frac{\partial V}{\partial x} \delta x\) is in the form of the potential energy term which appears in the Lagrange equations defined in the remainder of this document.

### 3.0 AN INTRODUCTION TO ENERGY METHODS IN DYNAMICS

Newton published the *Principia* in 1687, in which he laid down his three laws of motion. 101 years later, in 1788, Lagrange developed a way to derive the equations of motion by beginning with work and energy rather than force and momentum. One way to think about the leap from the statics problems described above and a dynamics problem is to consider what textbooks refer to as the work energy theorem, which may be stated as:

\[
(T_2 - T_1) + (V_2 - V_1) = W^{nc}_{1\rightarrow 2}
\] (3.1)

This states that the change in kinetic energy, \(T\), and potential energy, \(V\), as a dynamic system moves from state 1 to 2 is equal to the non-conservative work that is done by the external non-conservative forces applied to the system, as it moves from position 1 to 2. At all times in the movement of this system, the above statement must be true, if the system is in dynamic equilibrium. Another way of saying this is to say that the system would satisfy the equations of motion at all times.

Now imagine that at an instant in time, there is an infinitesimal variation in the position of the system from its natural dynamic equilibrium position. Just as is the case for the principal of virtual work for systems in static equilibrium, the net variation in the kinetic and potential energy and the work of the non-conservative forces would be zero. The variation in energy or work in each term is not zero, but the net sum is zero. Stated in equation form:

\[
\delta T + \delta V - \delta W^{nc} = 0
\]

Or if one prefers:

\[
\delta T + \delta V = \delta W^{nc}
\] (3.2)

The second expression says that the change in the sum of the kinetic and potential energies of the system must equal the work done by the external non-conservative forces. Lagrange discovered a way to express this for multiple degree of freedom systems. Before jumping directly to the equations, it is essential to carefully explain how one determines the correct number of necessary coordinates and degrees of freedom for any dynamical system that is to be modeled using the Lagrangian approach. There are even some dynamical systems for which Lagrange equations may not be used. One needs to know how to identify them.
4.0 GENERALIZED COORDINATES AND DEGREES OF FREEDOM

Generalized coordinates: The generalized coordinates of a mechanical system are the minimum group of parameters which can completely and unambiguously define the configuration of that system. They are called generalized because they are not restricted to being Cartesian coordinates and are not even required to be measured from an inertial reference frame. However, they are used to express the kinetic and potential energies of the rigid bodies which make up the dynamical system. The kinetic and potential energy must be computed with respect to an inertial reference frame. Therefore the generalized coordinates must be able to express the velocity and displacement of rigid bodies with respect to an inertial frame of reference.

Holonomic systems: A holonomic system is one in which the number of independent generalized coordinates required to describe the motion of the system equals the number of degrees of freedom. We study only holonomic systems in this class. An example of a non-holonomic system is given in lecture and others may be found in the text “Fundamentals of Applied Dynamics” by Prof. James H. Williams, Jr. An excerpt from that text, which describes Lagrangian dynamics in detail is available on the course Stellar website. You should study that after reading this introduction.

Degrees of freedom: The number of degrees of freedom of a system is the number of coordinates that can be independently varied in a small displacement. Said another way, the number of degrees of freedom is the same as the number of independent directions in which a system can move from any given initial configuration. Consider a system consisting of N rigid bodies in 2D space. Each rigid body has 3 degrees of freedom: two translational and one rotational. The N-body system has 3N degrees of freedom. Now let’s say that there are k kinematic constraints. Then the system has \( d = 3N - k \) degrees of freedom. For example a single uniform stick confined to a vertical, x-y plane has 3 degrees of freedom, x, y, and rotation, \( \vartheta \) about the z axis. It has no additional constraints. If we connect one end of the stick to a pivot, it now has two constraints, one in each of the x and y directions. It is still free to rotate. Therefore \( d = 3-2=1 \) dof. The motion of the pinned stick may be completely specified by one coordinate, the angle of rotation.

Completeness and Independence of generalized coordinates: In choosing which coordinates to use one must obey two requirements.

1. A set of generalized coordinates is complete, if it is capable of locating all parts of the system at all times.
2. A set of generalized coordinates is independent if, when all but one of the generalized coordinates are fixed, there remains a continuous range of values for that one coordinate.

There you have it. To find the equations of motion of a dynamical system using Lagrange equations, one must first determine the number of degrees of freedom, ‘d’, and then choose a set of ‘d’ generalized coordinates, which make up a complete and independent set.
5.0 THE LAGRANGE EQUATIONS

For a $j$-dof (degree-of-freedom) system with generalized coordinates $q_j$, it is possible to formulate the Lagrangian $L = T - V$ where $T$ is the kinetic energy and $V$ is the potential energy. The Lagrangian is a function of generalized coordinates $q_j$ and generalized velocities $\dot{q}_j$:

$$L = L(q_1, \ldots q_d, \dot{q}_1, \ldots \dot{q}_d)$$

where $d$ is the number of degrees of freedom. The Lagrange Equations are then:

$$\frac{d}{dt} \left( \frac{\partial L}{\partial \dot{q}_j} \right) - \frac{\partial L}{\partial q_j} = Q_j$$

where $Q_j$ are the external generalized forces. Since $j$ goes from 1 to $d$, Lagrange gives us $d$ equations of motion the same number as the degrees of freedom for the system.

The left hand side of Equation 4.2 is a function of only $T$ and $V$, the potential energy and kinetic energy and is straightforward to evaluate once the analyst has found $T$ & $V$. The right hand side is where most difficulties arise. The right hand side requires that one take the real non-conservative forces that one would specify on a free body diagram and re-express them in terms of the component of the real forces that act in the direction of each generalized deflection. This is the process of finding the generalized forces.

6.0 FINDING THE GENERALIZED FORCES

Let’s consider first just one external real force, applied at some point on the body. An example, borrowed from Williams is shown in the figure below. It is a hinged rigid link, which is acted upon by an external force, $F(t)$ which always points down. This system has one degree of freedom and therefore the angle, $\theta$, that the link makes with the vertical has been specified as a complete and independent set of generalized coordinates. $q_j = q_i = \theta$

For this example, $\delta q_i = \delta \theta$, a small virtual variation in $\theta$.

$Q_i \delta \theta = F \cdot \delta r =$ the work done by the external force $F$

during the variation $\delta \theta$. The magnitude of the generalized force, $Q_1$, associated with the virtual deflection of the system, $\delta \theta$, may be obtained by finding the virtual work done by the real force $F(t)$ in the course of the virtual displacement.

In equation form, the work done is the dot product of the applied external force, $F(t)$, and the virtual deflection in the direction of the generalized coordinate which is going through the variation $\delta \theta$. In this case the generalized coordinate is $\theta$, and the deflection component in the direction of $F(t)$ is $l \sin(\theta) \delta \theta$, as shown in part c of the figure below. The virtual work done during this small variation is given by
\[ \delta W^v = Q_1 \delta \theta = F(t)l \sin(\theta) \delta \theta \]

Therefore

\[ Q_1 = F(t)l \sin(\theta) \]

In this example, the actual displacement at the location of and in the direction of the force \( F(t) \) is given by \( l \sin(\theta) \delta \theta \), as shown in the diagram above.

For many problems the dot product of the external force and the deflection component in the direction of each generalized displacement may be deduced by common sense as was done above. Several examples are given in the chapter by Williams and more will be done in lecture.

In the above example the system had only one degree of freedom and therefore there was only one virtual displacement of the single coordinate \( \theta \). In general there will be many coordinates and many applied external forces. We need to broaden the approach to account for this.

At every point of application of a real external force, \( F_i \), to the system work will be done if that point moves. Some external forces like those produced by gravity or lossless springs are usually included in the potential energy expression. We will assume so here. The ones remaining are called non-conservative forces because they may add or extract energy from the system. The technique used to evaluate these non-conservative generalized forces is to assume the system undergoes a small virtual deflection for which we compute the increment or variation in work that results, as expressed in the following
equation, which says that the total variation in the work of the non-conservative forces is
given by the sum of the dot products of the external forces with the total virtual deflection
at the location of each force, due to the combined virtual deflections of each coordinate.

\[
\delta W_{nc}^{\text{total}} = \sum_{i=1}^{N} F_i \cdot \delta r_i (\delta q_1, \delta q_2, \ldots, \delta d) = \sum_{j=1}^{d} Q_j \delta q_j
\] (4.4)

The term on the right of equation 4.4 says that the same total variation in the work done
by the non-conservative forces must equal the sum of the generalized forces, \(Q_j\)
multiplied the virtual displacement \(\delta q_j\) associated with that generalized force. In this
course we will do problems for which we can separate out the individual terms by
applying geometry and simple vectors. We will in general consider the virtual work done
by considering the variation of one coordinate at a time and from that deduce the
generalized force associated with that motion.

A more rigorous method exists which is described in a brief appendix at the end of this
paper.

In summary, some key points to remember regarding generalized forces are:

- Forces of constraint which do no work can be ignored because they will always be
  perpendicular to allowable motions, also known as admissible motions. Examples
  include the internal forces in a rigid body, the forces of reaction in friction-less
  sliding, and so on.
- Forces which derive from a potential function like gravity or a spring can be
  considered in potential energy, \(V\). They too can be ignored when computing
generalized forces.
- Forces which are neither included in the computation of potential energy nor are
  workless forces of constraint must be expressed as non-conservative generalized
  forces in the Lagrange formulation. Examples include dissipative forces from
dashpots, external excitations. If one mistakenly accounts for a potential force as
a non-conservative force, it will work out just fine in the end, as long as you don’
also account for it in the potential energy expression.

7.0 USING LAGRANGE’S EQUATIONS

Now we can return to the Lagrange equations as given in Equation 4.2.

\[
\frac{d}{dt} \left( \frac{\partial L}{\partial \dot{q}_j} \right) - \frac{\partial L}{\partial q_j} = Q_j
\] (4.5)

Mathematicians like the elegance of this expression, but it obscures some of the physics.
Lagrange was proud of the fact that his 1788 treatise did not contain a single diagram.
Let’s reconnect it to the physics. Recall that the Lagrangian, \( L \), is defined as \( L = T - V \). Substitution in the above equation yields:

\[
\frac{d}{dt} \left( \frac{\partial (T - V)}{\partial \dot{q}_j} \right) - \frac{\partial (T - V)}{\partial q_j} = \frac{d}{dt} \left( \frac{\partial (T)}{\partial \dot{q}_j} \right) - \frac{\partial (T)}{\partial q_j} + \frac{\partial (V)}{\partial \dot{q}_j} + \frac{\partial (V)}{\partial q_j} = Q_j \quad \text{a.}
\]

Noting that \( \frac{d}{dt} \left( \frac{\partial (V)}{\partial \dot{q}_j} \right) = 0 \) for common mechanical systems,

\[
\Rightarrow \frac{d}{dt} \left( \frac{\partial (T)}{\partial \dot{q}_j} \right) - \frac{\partial (T)}{\partial q_j} + \frac{\partial (V)}{\partial \dot{q}_j} = Q_j \quad \text{b.}
\]

Multiplying by \( \delta q_j \) \( \Rightarrow \) (4.6)

\[
\left[ \frac{d}{dt} \left( \frac{\partial (T)}{\partial \dot{q}_j} \right) - \frac{\partial (T)}{\partial q_j} \right] \delta q_j + \frac{\partial (V)}{\partial \dot{q}_j} \delta q_j = Q_j \delta q_j \quad \text{c.}
\]

This is of the form

\[
\delta T + \delta V = \delta W_{nc} \quad \text{d.}
\]

In common mechanical systems, potential energy accounts for gravitational potential energy or the potential energy stored in springs. The potential energy for such systems is never a function of velocity, and hence the term \( \frac{d}{dt} \left( \frac{\partial (V)}{\partial \dot{q}_j} \right) \) vanishes in the above equations. For simple mechanical systems the term \( -\frac{\partial (T)}{\partial q_j} \) is often zero. The form of Lagrange equations expressed above in terms of \( T \) and \( V \) and not \( L \) is therefore easier to use and requires less wasteful bookkeeping. It may be used for all mechanical problems of the kind done in this course. When one should be cautious with this simplification is when there are potential forces involving charged particles and/or electric currents and magnetic fields. Then the assumption that \( \frac{d}{dt} \left( \frac{\partial (V)}{\partial \dot{q}_j} \right) \) vanishes is not valid.

The steps in computing the equations of motion using Lagrange’s method are below.

**Start with the LHS of Equation 4.2 or the more direct 4.6b:**

1. Identify the generalized coordinates. Make sure that you have just as many as there are degrees-of-freedom and confirm that the system is holonomic.

2. Compute the kinetic energy \( T \) as a function of \( q_j \)'s and \( \dot{q}_j \)'s.
3. Compute the potential energy \( V \) as a function of \( q_j \)'s. Clearly designate the forces which you will call out as potential and forces and those which you will call out as non-conservative external forces.

4. Compute separately \( \frac{d}{dt} \left( \frac{\partial T}{\partial \dot{q}_j} \right), \frac{\partial T}{\partial q_j} \) and \( \frac{\partial V}{\partial q_j} \) for each generalized coordinate and from the sum of the three pieces you will have the LHS of the equation of motion associated with each generalized coordinate \( j \), as given in equation 4.6b. The LHS by itself represents the equations of motion of the system without the action of external non-conservative forces. It is useful by itself in understanding the system.

Now the RHS of Equation 4.2 and 4.6b:

1. Identify all non-conservative forces. They may be many or few and have nothing to do with the number of degrees of freedom in the problem.

2. Number them as \( i = 1, 2, \ldots, n \). Call the forces \( F_1, F_2, \ldots, F_n \).

3. For each \( j \), compute the virtual work associated with the virtual deflection of each generalized coordinate. \( Q_j \delta q_j = \sum_i F_i \delta r_i (\delta q_j) \) where each \( \delta r_i \) is a function of but not necessarily equal to \( \delta q_j \) as was true in the first example which considered the motion of the hinged link. The RHS of this expression will be of the form \( [] \delta q_j \), where the term in [ ] will involve the real forces, \( F_i \), and geometry. This term \( [ ] = Q_j \) the generalized force you are seeking to put into the RHS of equation 4.6b or equation 4.2.

4. For more difficult problems employ the explicit computation prescribed by the equation: \( Q_j \delta q_j = \sum_{i=1}^N F_i \cdot \left( \frac{\partial r_i}{\partial q_j} \right) \delta q_j \) which is described in the appendix.

5. Now equate the LHS to RHS of equation 4.6b for each \( j \). You will finish with \( d \) equations of motion, one for each degree of freedom.

The final step is to put this to practice doing lots of examples. Examples are to be found in lecture, in the course problem sets and in the text by Williams.

### 8.0 ADVANTAGES AND DISADVANTAGES OF LAGRANGE

**Advantages:**

1. The Lagrange Approach automatically yields as many equations as there are degrees of freedom.
2. The Lagrange equations naturally use the generalized coordinates of the system. By contrast, Newton’s Equations are essentially Cartesian. You end up having to convert everything into Cartesian components of acceleration and Cartesian components of forces to use Newton’s Equation. Lagrange bypasses that conversion.

3. The Lagrange approach naturally eliminates forces of constraint. You could do the same with the direct (Newtonian) approach, but your ability to minimize the number of variables depends very much on your skill; Lagrange takes care of it for you automatically because the generalized forces only include force components in directions of admissible motion.

Disadvantages:

1. If you make mistakes in formulation of $T$, $V$ and $W^{nc}$ you may never notice. The physics of forces and free body diagrams is easily overlooked. One should always evaluate each of the equations obtained by the Lagrange method and question whether or not it makes physical sense. Do the expected accelerations occur? For example for systems which rotate are there the expected centripetal and/or coriolis accelerations.

2. Computation of the generalized forces can be as much or more work in the Lagrangian method as in the direct method.

**APPENDIX: A KINEMATICS APPROACH TO COMPUTING GENERALIZED FORCES**

In order to use the Lagrange method one must find the Generalized forces, $Q_j$. What one must identify first are the external forces, $F_i$, and then must find a way to express the arbitrary virtual displacement $\delta r_i$ in terms of the variations of the generalized displacements, $\delta q_j$.

The generalized force $Q_j$ is defined below:

$$Q_j = \sum_{i=1}^{N} F_i \cdot \left( \frac{\partial r_i}{\partial q_j} \right) \quad (4.5)$$

where $F_i$ is the vector force at point $i$ and $r_i$ is the position vector to point $i$, measured with respect to an inertial frame of reference. The index $j$ corresponds to each of the generalized coordinates, which must be evaluated one at a time. The summation over $i$ accounts for the fact that there may be more than one real force, $F_i$, which does work when the virtual displacement $\delta q_j$ takes place. It is the total of all these contributions that makes up the generalized force $Q_j$. The total virtual work associated with the virtual displacement $\delta q_j$ is the sum of the virtual work done by each of the real forces $F_i$. 

as a result of the virtual displacement $\delta q_j$.

$$\delta W^nc_j = Q_j \delta q_j = \sum_{i=1}^{N} F_i \cdot \left( \frac{\partial \mathbf{r}_i}{\partial q_j} \right) \delta q_j$$  \hspace{1cm} (4.6)

At the location of $F_i$ a small variation of $\delta q_j$ results in a deflection at $i$ in the $j$ direction, $\delta r_{ij}$, given by:

$$\delta r_{ij} = \frac{\partial \mathbf{r}_i}{\partial q_j} \delta q_j$$  \hspace{1cm} (4.7)

$\delta r_{ij}$ is never in the direction of a kinematic constraint, because no virtual displacement is allowed in the direction of a constraint. In general, for a $d$-degree-of-freedom system with generalized coordinates $q_1, ..., q_d$, the total admissible motion at a point $i$ with position vector $\mathbf{r}_i$ is given by a summation over the contributions from the small virtual deflection of every generalized coordinate that affects the motion at position $i$, as specified below.

$$\delta \mathbf{r}_i = \sum_{j=1}^{d} \frac{\partial \mathbf{r}_{ij}}{\partial q_j} \delta q_j$$  \hspace{1cm} (4.8)
Example 1

This example considers a single non-conservative force acting on a one degree of freedom system.

Consider the generalized forces in this system of two masses. Although there are two masses, only one variable is needed to completely fix the configuration, which implies that there is a single degree of freedom. There are two possibilities: $\theta$ or $x$, as defined by the figure. Now we can address the generalized forces. Only one non-conservative is present that we need to account for: the dashpot.

If we have chosen to use $\theta$ to describe the system, we need to find the amount of virtual work that the non-conservative force will do for a virtual displacement in $\theta$. In order to find this, we first need to express the point of the system where the non-conservative force is acting, $O_B$ in terms of $\theta$: $O_B = 2l \cos(\theta) \hat{I}$. Intuitively obtaining $\delta O_B$ from a small deflection $\delta \theta$ is not very clear, so we can use equation 4.7 from above:

$$\delta O_B = \frac{\partial O_B}{\partial \theta} \delta \theta = (-2l \sin(\theta)) \hat{I} \delta \theta$$

With this relation, we can then look at the generalized force:

$$\delta W^{nc} = F \cdot \delta r = -c\dot{x} \hat{I} \cdot (-2l \sin(\theta)) \hat{I} \delta \theta = 2cl\dot{x} \sin(\theta) \delta \theta = -4cl^2 \sin^2(\theta) \dot{\theta} \delta \theta = Q_\theta \delta \theta$$

From this, we see that the generalized force is equal to $-4cl^2 \sin^2(\theta) \dot{\theta}$, where we had to find $\dot{x}$ in terms of $\dot{\theta}$. 
If we had instead chosen to use $x$ to describe our system, the calculation for the corresponding generalized force would have been more straightforward (at the expense of more complications elsewhere in finding the EoM). In this case, $^0r_B = x\hat{I}$, so we can see that a virtual displacement $\delta x$ will immediately create a displacement in the point where the non-conservative force is acting by the same amount $\delta x\hat{I}$. Therefore:

$$\delta W^{nc} = F \cdot \delta r$$
$$= -c\dot{x}\hat{I} \cdot \delta x\hat{I}$$
$$= = -c\dot{x}\delta x$$
$$= Q_x\delta x$$

So we find that the generalized force associated with the dashpot in $x$ is equal to $-c\dot{x}$.

**Example 2**

In this example, we consider a single non-conservative force acting on a more complicated two degree of freedom problem.

This problem has two degrees of freedom, which we will take to correspond to the $\theta$ and $x$ generalized coordinates defined in the figure. The non-conservative force $F(t)$ acts on the center of mass of the ball in the $\hat{I}$ direction. In order to find the generalized forces (corresponding to each generalized coordinate), we can still use the two approaches discussed earlier.

In the first approach, we consider the virtual deflection of the point of action of the force and how it is affected by each general coordinate’s independent virtual deflection.
Consider a small deflection $\delta \theta$ first. Clearly from the figure, this causes a rotation about point $O$, and since the length of the pendulum for a (temporarily) fixed value of $x$ is $l_0 + x$, the displacement of the point of contact due to $\delta \theta$ is $(l_0 + x) \hat{\theta} \delta \theta$, where $\hat{\theta}$ is a unit vector perpendicular to the long axis of the pendulum. If we now hold fixed the angle $\theta$ and allow a small displacement $\delta x$, then the point of contact displaces by $\delta x \hat{r}$, where $\hat{r}$ is parallel to the long axis of the pendulum. Combining these results, we find:

$$
\delta^O r_C = \delta x \hat{r} + (l_0 + x) \hat{\theta} \delta \theta \\
= \delta x \left( \sin (\theta) \hat{\mathbf{i}} - \cos (\theta) \hat{\mathbf{j}} \right) + (l_0 + x) \delta \theta \left( \cos (\theta) \hat{\mathbf{i}} + \sin (\theta) \hat{\mathbf{j}} \right)
$$

$$
F \cdot \delta^O r_C = F \hat{\mathbf{i}} \cdot \left( \delta x \left( \sin (\theta) \hat{\mathbf{i}} - \cos (\theta) \hat{\mathbf{j}} \right) + (l_0 + x) \delta \theta \left( \cos (\theta) \hat{\mathbf{i}} + \sin (\theta) \hat{\mathbf{j}} \right) \right) \\
= F \sin (\theta) \delta x + F (l_0 + x) \cos (\theta) \delta \theta \\
= Q_x \delta x + Q_\theta \delta \theta
$$

So we find that the general force associated with the $x$ general coordinate is $F \sin (\theta)$ and the one associated with the $\theta$ general coordinate is $F (l_0 + x) \cos (\theta)$. Note that the correct units (Newtons for the linear coordinate and Newton-meters for the angular coordinate) fell out directly from solving for the generalized forces.

In the second approach, we can find the generalized forces more directly, but first need an expression for the position where the non-conservative force acts.

$$
^O r_C = (l_0 + x) \hat{r} = (l_0 + x) \left( \sin (\theta) \hat{\mathbf{i}} - \cos (\theta) \hat{\mathbf{j}} \right)
$$

From equation 4.6 above, we can find that the generalized force for the generalized coordinate $x$ is given by $\sum_{i=1}^{N} F_i \cdot \frac{\partial}{\partial x}$, where $N$ is the number of non-conservative forces (one in this case). A similar expression finds the generalized force for the generalized coordinate $\theta$. Evaluating these, we find:

$$
Q_x = F \cdot \frac{\partial^O r_C}{\partial x} \\
= F \hat{\mathbf{i}} \cdot \left( \sin (\theta) \hat{\mathbf{i}} - \cos (\theta) \hat{\mathbf{j}} \right) \\
= F \sin (\theta)
$$

$$
Q_\theta = F \cdot \frac{\partial^O r_C}{\partial \theta} \\
= F \hat{\mathbf{i}} \cdot (l_0 + x) \left( \cos (\theta) \hat{\mathbf{i}} + \sin (\theta) \hat{\mathbf{j}} \right) \\
= F (l_0 + x) \cos (\theta)
$$

These results match the earlier results, as expected. However, this approach required writing out an explicit expression for the point of application for each non-conservative
force in terms of all the generalized forces. This means that while there are multiple valid ways of expressing the position of the application of the force, only some of these expressions will be useful in this approach. For example, writing the position vector in terms of the \( \hat{r} \) unit vector only does not explicitly depend on the angle \( \theta \) since that information is contained in the direction of \( \hat{r} \) unit vector.