

Contents

<i>Preface</i>	xv
----------------	----

1 Galileo	1
------------------	----------

1.1 Principle of Galilean relativity	2
1.2 Galilean transformations	3
1.2.1 Admissible force laws for an N -particle system	6
1.3 Subgroups of the Galilean transformations	8
1.3.1 Matrix representation of $SE(3)$	9
1.4 Lie group actions of $SE(3)$	11
1.5 Lie group actions of $G(3)$	12
1.5.1 Matrix representation of $G(3)$	14
1.6 Lie algebra of $SE(3)$	15
1.7 Lie algebra of $G(3)$	17

2 Newton, Lagrange, Hamilton and the rigid body	19
--	-----------

2.1 Newton	21
2.1.1 Newtonian form of free rigid rotation	21
2.1.2 Newtonian form of rigid-body motion	30
2.2 Lagrange	36
2.2.1 The principle of stationary action	36
2.3 Noether's theorem	39
2.3.1 Lie symmetries and conservation laws	39

2.3.2	Infinitesimal transformations of a Lie group	40
2.4	Lagrangian form of rigid-body motion	46
2.4.1	Hamilton–Pontryagin constrained variations	50
2.4.2	Manakov’s formulation of the $SO(n)$ rigid body	54
2.4.3	Matrix Euler–Poincaré equations	55
2.4.4	An isospectral eigenvalue problem for the $SO(n)$ rigid body	56
2.4.5	Manakov’s integration of the $SO(n)$ rigid body	58
2.5	Hamilton	60
2.5.1	Hamiltonian form of rigid-body motion	62
2.5.2	Lie–Poisson Hamiltonian rigid-body dynamics	63
2.5.3	Lie–Poisson bracket	64
2.5.4	Nambu’s $\mathbb{R}^3$ Poisson bracket	65
2.5.5	Clebsch variational principle for the rigid body	69
2.5.6	Rotating motion with potential energy	72

3 Quaternions

77

3.1	Operating with quaternions	78
3.1.1	Multiplying quaternions using Pauli matrices	79
3.1.2	Quaternionic conjugate	82
3.1.3	Decomposition of three-vectors	85
3.1.4	Alignment dynamics for Newton’s second law	86
3.1.5	Quaternionic dynamics of Kepler’s problem	90
3.2	Quaternionic conjugation	93
3.2.1	Cayley–Klein parameters	93
3.2.2	Pure quaternions, Pauli matrices and $SU(2)$	99
3.2.3	Tilde map: $\mathbb{R}^3 \simeq su(2) \simeq so(3)$	102
3.2.4	Dual of the tilde map: $\mathbb{R}^{3*} \simeq su(2)^* \simeq so(3)^*$	103
3.2.5	Pauli matrices and Poincaré’s sphere $\mathbb{C}^2 \rightarrow S^2$	103
3.2.6	Poincaré’s sphere and Hopf’s fibration	105

3.2.7	Coquaternions	108
-------	---------------	-----

4 Adjoint and coadjoint actions 111

4.1	Cayley–Klein dynamics for the rigid body	112
4.1.1	Cayley–Klein parameters, rigid-body dynamics	112
4.1.2	Body angular frequency	113
4.1.3	Cayley–Klein parameters	115
4.2	Actions of quaternions, Lie groups and Lie algebras	116
4.2.1	AD , Ad , ad , Ad^* and ad^* actions of quaternions	117
4.2.2	AD , Ad , and ad for Lie algebras and groups	118
4.3	Example: The Heisenberg Lie group	124
4.3.1	Definitions for the Heisenberg group	124
4.3.2	Adjoint actions: AD , Ad and ad	126
4.3.3	Coadjoint actions: Ad^* and ad^*	127
4.3.4	Coadjoint motion and harmonic oscillations	129

5 The special orthogonal group $SO(3)$ 131

5.1	Adjoint and coadjoint actions of $SO(3)$	132
5.1.1	Ad and ad operations for the hat map	132
5.1.2	AD , Ad and ad actions of $SO(3)$	133
5.1.3	Dual Lie algebra isomorphism	135

6 Adjoint and coadjoint semidirect-product group actions 141

6.1	Special Euclidean group $SE(3)$	142
6.2	Adjoint operations for $SE(3)$	144
6.3	Adjoint actions of $SE(3)$'s Lie algebra	148
6.3.1	The ad action of $se(3)$ on itself	148
6.3.2	The ad^* action of $se(3)$ on its dual $se(3)^*$	149

6.3.3	Left versus right	151
6.4	Special Euclidean group $SE(2)$	153
6.5	Semidirect-product group $SL(2, \mathbb{R}) \otimes \mathbb{R}^2$	156
6.5.1	Definitions for $SL(2, \mathbb{R}) \otimes \mathbb{R}^2$	156
6.5.2	AD, Ad, and ad actions	158
6.5.3	Ad* and ad* actions	160
6.5.4	Coadjoint motion relation	162
6.6	Galilean group	164
6.6.1	Definitions for $G(3)$	164
6.6.2	AD, Ad, and ad actions of $G(3)$	165
6.7	Iterated semidirect products	167

7 Euler–Poincaré and Lie–Poisson equations on $SE(3)$ 169

7.1	Euler–Poincaré equations for left-invariant Lagrangians under $SE(3)$	170
7.1.1	Legendre transform from $se(3)$ to $se(3)^*$	172
7.1.2	Lie–Poisson bracket on $se(3)^*$	172
7.1.3	Coadjoint motion on $se(3)^*$	173
7.2	Kirchhoff equations on $se(3)^*$	176
7.2.1	Looks can be deceiving: The heavy top	178

8 Heavy-top equations 181

8.1	Introduction and definitions	182
8.2	Heavy-top action principle	183
8.3	Lie–Poisson brackets	184
8.3.1	Lie–Poisson brackets and momentum maps	185
8.3.2	Lie–Poisson brackets for the heavy top	186
8.4	Clebsch action principle	187
8.5	Kaluza–Klein construction	188

9 The Euler–Poincaré theorem 193

- 9.1 Action principles on Lie algebras 194
- 9.2 Hamilton–Pontryagin principle 198
- 9.3 Clebsch approach to Euler–Poincaré 199
 - 9.3.1 Defining the Lie derivative 201
 - 9.3.2 Clebsch Euler–Poincaré principle 202
- 9.4 Lie–Poisson Hamiltonian formulation 206
 - 9.4.1 Cotangent-lift momentum maps 207

10 Lie–Poisson Hamiltonian form of a continuum spin chain 209

- 10.1 Formulating continuum spin chain equations 210
- 10.2 Euler–Poincaré equations 212
- 10.3 Hamiltonian formulation 213

11 Momentum maps 221

- 11.1 The momentum map 222
- 11.2 Cotangent lift 224
- 11.3 Examples of momentum maps 226
 - 11.3.1 The Poincaré sphere $S^2 \in S^3$ 237
 - 11.3.2 Overview 242

12 Round, rolling rigid bodies 245

- 12.1 Introduction 246
 - 12.1.1 Holonomic versus nonholonomic 246
 - 12.1.2 The Chaplygin ball 248
- 12.2 Nonholonomic Hamilton–Pontryagin variational principle 252
 - 12.2.1 HP principle for the Chaplygin ball 256

12.2.2 Circular disk rocking in a vertical plane	265
12.2.3 Euler's rolling and spinning disk	268
12.3 Nonholonomic Euler–Poincaré reduction	275
12.3.1 Semidirect-product structure	276
12.3.2 Euler–Poincaré theorem	278
12.3.3 Constrained reduced Lagrangian	282

A Geometrical structure of classical mechanics 287

A.1 Manifolds	288
A.2 Motion: Tangent vectors and flows	296
A.2.1 Vector fields, integral curves and flows	297
A.2.2 Differentials of functions: The cotangent bundle	299
A.3 Tangent and cotangent lifts	300
A.3.1 Summary of derivatives on manifolds	301

B Lie groups and Lie algebras 305

B.1 Matrix Lie groups	306
B.2 Defining matrix Lie algebras	310
B.3 Examples of matrix Lie groups	312
B.4 Lie group actions	314
B.4.1 Left and right translations on a Lie group	316
B.5 Tangent and cotangent lift actions	317
B.6 Jacobi–Lie bracket	320
B.7 Lie derivative and Jacobi–Lie bracket	323
B.7.1 Lie derivative of a vector field	323
B.7.2 Vector fields in ideal fluid dynamics	325

C Enhanced coursework 327

C.1 Variations on rigid-body dynamics	328
---------------------------------------	-----

C.1.1	Two times	328
C.1.2	Rotations in complex space	334
C.1.3	Rotations in four dimensions: $SO(4)$	338
C.2	$\mathbb{C}^3$ oscillators	343
C.3	Momentum maps for $GL(n, \mathbb{R})$	348
C.4	Motion on the symplectic Lie group $Sp(2)$	354
C.5	Two coupled rigid bodies	359

D	Poincaré's 1901 paper	363
----------	------------------------------	------------

<i>Bibliography</i>	367
---------------------	-----

<i>Index</i>	385
--------------	-----