

# DYNAMICS OF CONSTRAINED MECHANICAL SYSTEMS

约束力学系统动力学 (英文版)

Mei Fengxiang Wu Huibin



北京理工大学出版社  
BEIJING INSTITUTE OF TECHNOLOGY PRESS

责任编辑：刘小亦

封面设计：庚辰年代

定价：90.00 元

ISBN 978-7-5640-2168-9



A standard linear barcode representing the ISBN 978-7-5640-2168-9.

9 787564 021689 >

0316/Y10

2009.

# DYNAMICS OF CONSTRAINED MECHANICAL SYSTEMS

## 约束力学系统动力学 (英文版)

Mei Fengxiang Wu Huibin



北京理工大学出版社  
BEIJING INSTITUTE OF TECHNOLOGY PRESS

## 内 容 简 介

本书系统地阐述了约束力学系统的变分原理、运动方程、相关专门问题的理论与应用、积分方法、对称性与守恒量等内容，具有很高的学术价值，为方便国际学术交流，译成英文出版。全书共分为六个部分：

第一部分：约束力学系统的基本概念。本部分包含 6 章，介绍分析力学的主要基本概念；第二部分：约束力学系统的变分原理。本部分有 5 章，阐述微分变分原理、积分变分原理以及 Pfaff-Birkhoff 原理；第三部分：约束力学系统的运动微分方程。本部分共 11 章，系统介绍完整系统、非完整系统的各类运动方程；第四部分：约束力学系统的专门问题。本部分有 8 章，讨论运动稳定性和微扰理论、刚体定点转动、相对运动动力学、可控力学系统动力学、打击运动动力学、变质量系统动力学、机电系统动力学、事件空间动力学等内容；第五部分：约束力学系统的积分方法。本部分有 6 章，介绍降阶方法、动力学代数与 Poisson 方法、正则变换、Hamilton-Jacobi 方法、场方法、积分不变量；第六部分：约束力学系统的对称性与守恒量。本部分共 10 章，讨论 Noether 对称性、Lie 对称性、形式不变性，以及由它们导致的各种守恒量。

本书的出版必将引起国内外同行的关注，对该领域的发展将起到重要的推动作用。

版权专有 侵权必究

## 图书在版编目 (CIP) 数据

约束力学系统动力学 = Dynamics of Constrained Mechanical Systems:  
英文 / 梅凤翔, 吴惠彬著. —北京: 北京理工大学出版社, 2009. 4  
ISBN 978--7--5640--2168--9

I. 约… II. ①梅… ②吴… III. 分析力学—英文 IV. O316

中国版本图书馆 CIP 数据核字 (2009) 第 063623 号

---

出版发行 / 北京理工大学出版社  
社 址 / 北京市海淀区中关村南大街 5 号  
邮 编 / 100081  
电 话 / (010)68914775(办公室) 68944990(批销中心) 68911084(读者服务部)  
网 址 / <http://www.bitpress.com.cn>  
经 销 / 全国各地新华书店  
印 刷 / 保定市中画美凯印刷有限公司  
开 本 / 787 毫米×1092 毫米 1/16  
印 张 / 39  
插 页 / 1  
字 数 / 1191 千字  
版 次 / 2009 年 4 月第 1 版 2009 年 4 月第 1 次印刷 责任校对 / 申玉琴  
定 价 / 90.00 元 责任印制 / 边心超

---

图书出现印装质量问题，本社负责调换

## Preface

This book is entitled *Dynamics of Constrained Mechanical Systems*. The constrained mechanical systems, in my opinion, contain the three kinds of the systems, i.e. the holonomic systems, the nonholonomic systems and the Birkhoff systems. The book covers the following six parts.

Part I Fundamental Concepts in Constrained Mechanical Systems. The part has 6 chapters: Constraints and their classification, Generalized coordinates, Quasi-velocities and quasi-coordinates, Virtual displacements, Ideal constraints, Transpositional relations of differential and variational operators.

Part II Variational Principles in Constrained Mechanical Systems. It covers 5 chapters: Differential variational principles, Integral variational principles in terms of generalized coordinates for holonomic systems, Integral variational principles in terms of quasi-coordinates for holonomic systems, Integral variational principles for nonholonomic systems, Pfaff-Birkhoff principle.

Part III Differential Equations of Motion of Constrained Mechanical Systems. It covers 11 chapters: Lagrange equations of holonomic systems, Lagrange equations with multiplier for nonholonomic systems, Mac Millan equations for nonholonomic systems, Volterra equations for nonholonomic systems, Chaplygin equations for nonholonomic systems, Boltzmann-Hamel equations for nonholonomic systems, Euler-Lagrange equations for higher order honholonomic systems, Nielsen equations, Appell equations, Equations of motion of mixed type, Canonical equations.

Part IV Special Problems in Constrained Mechanical Systems. It covers 8 chapters: Stability of motion and theory of small oscillations, Dynamics of rigid body with fixed point, Dynamics of relative motion, Dynamics of controllable mechanical systems, Dynamics of impulsive motion, Dynamics of variable mass systems, Dynamics of electromechanical systems, Dynamics in event space.

Part V Integration Methods in Constrained Mechanical Systems. It covers 6 chapters: Methods of reduction of order, Dynamics algebra and Poisson method, Canonical transformations, Hamilton-Jacobi method, Field method, Integral invariants.

Part VI Symmetries and Conserved Quantities in Constrained Mechanical Systems. The part has 10 chapters: Noether symmetries and conserved quantities, Lie symmetries and Hojman conserved quantities, Form invariance and new conserved quantities, Noether symmetries and Hojman conserved quantities, Noether symmetries and new conserved quantities, Lie symmetries and Noether conserved quantities, Lie symmetries and new conserved quantities, Form invariance and Noether conserved quantities, Form invariance and Hojman conserved quantities, Unified symmetries and conserved quantities.

The emphatic discussions in the book are: the equations of motion of nonholonomic systems; the theory and application of special problems; the integral methods and the symmetries and conservative quantities.

The mathematics tools in the book are simple. Advanced mathematics, such as modern differential geometry, are not involved. Interested readers can read some relative reference books.

The book is addressed to graduate students, professors and researchers in the areas of applied mechanics, applied mathematics and applied physics.

In spring of 1963, I began to learn the knowledge of nonholonomic mechanics and finished my graduate dissertation under the direction of Professor Lu Yiling in Peking University. In autumn of 1981 I visited the Laboratoire de Mécanique Théorique in Université de Besançon, presented my work on the nonholonomic mechanics, and obtained the direction of Professor Capodanno. P. In spring of 1982, I finished my Thèse de Doctorat d'Etat under the direction of Professor Pironneau I in ENSM at Nantes France.

The great majority of my papers and my books are published in Chinese. In order to exchange experience of study on dynamics of constrained mechanical systems, I decide to write this English book. This book is written by myself and my colleague Dr Wu Huibin.

## **Acknowledgments**

I express my deep appreciation and thanks to Papastavridis J G, Professor at Georgia Institute of Technology, for his great book *Analytical Mechanics* and his support; Zhu Zhaoxuan, Professor at Peking University, for his direction and suggestion.

The publication of this book is supported by the Beijing Municipal Key Disciplines Fund for General Mechanics and Foundation of Mechanics, and the National Natural Science Foundation of China(10572021, 10772025).

Mei Fengxiang  
November 2008  
in Beijing

# Contents

<b>I</b>	<b>Fundamental Concepts in Constrained Mechanical Systems</b>	<b>1</b>
<b>1</b>	<b>Constraints and Their Classification</b>	<b>3</b>
1.1	Constraints . . . . .	3
1.2	Equations of Constraint . . . . .	3
1.3	Classification of Constraints . . . . .	4
1.3.1	Holonomic Constraints and Nonholonomic Constraints . . . . .	5
1.3.2	Stationary Constraints and Non-stationary Constraints . . . . .	6
1.3.3	Unilateral Constraints and Bilateral Constraints . . . . .	6
1.3.4	Passive Constraints and Active Constraints . . . . .	7
1.4	Integrability Theorem of Differential Constraints . . . . .	7
1.5	Generalization of the Concept of Constraints . . . . .	10
1.5.1	First Integral as Nonholonomic Constraints . . . . .	11
1.5.2	Controllable System as Holonomic or Nonholonomic System . . . . .	11
1.5.3	Nonholonomic Constraints of Higher Order . . . . .	11
1.5.4	Restriction on Change of Dynamical Properties as Constraint . . . . .	11
1.6	Remarks . . . . .	12
<b>2</b>	<b>Generalized Coordinates</b>	<b>13</b>
2.1	Generalized Coordinates . . . . .	13
2.2	Generalized Velocities . . . . .	14
2.3	Generalized Accelerations . . . . .	15
2.4	Expression of Equations of Nonholonomic Constraints in Terms of Generalized Coordinates and Generalized Velocities . . . . .	16
2.5	Remarks . . . . .	17
<b>3</b>	<b>Quasi-Velocities and Quasi-Coordinates</b>	<b>19</b>
3.1	Quasi-Velocities . . . . .	19
3.2	Quasi-Coordinates . . . . .	21
3.3	Quasi-Accelerations . . . . .	22
3.4	Remarks . . . . .	23
<b>4</b>	<b>Virtual Displacements</b>	<b>25</b>
4.1	Virtual Displacements . . . . .	25
4.1.1	Concept of Virtual Displacements . . . . .	25
4.1.2	Condition of Constraints Exerted on Virtual Displacements . . . . .	25
4.1.3	Degree of Freedom . . . . .	27
4.2	Necessary and Sufficient Condition Under Which Actual Displacement Is One of Virtual Displacements . . . . .	27
4.3	Generalization of the Concept of Virtual Displacement . . . . .	28

4.4	Remarks . . . . .	30
<b>5</b>	<b>Ideal Constraints</b>	<b>31</b>
5.1	Constraint Reactions . . . . .	31
5.2	Examples of Ideal Constraints . . . . .	32
5.3	Importance and Possibility of Hypothesis of Ideal Constraints . . . . .	32
5.4	Remarks . . . . .	33
<b>6</b>	<b>Transpositional Relations of Differential and Variational Operations</b>	<b>35</b>
6.1	Transpositional Relations for First Order Nonholonomic Systems . . . . .	35
6.1.1	Transpositional Relations in Terms of Generalized Coordinates . . . . .	35
6.1.2	Transpositional Relations in Terms of Quasi-Coordinates . . . . .	37
6.2	Transpositional Relations of Higher Order Nonholonomic Systems . . . . .	41
6.2.1	Transpositional Relations in Terms of Generalized Coordinates . . . . .	41
6.2.2	Transpositional Relations in Terms of Quasi-Coordinates . . . . .	42
6.3	Vujanović Transpositional Relations . . . . .	43
6.3.1	Transpositional Relations for Holonomic Nonconservative Systems . . . . .	43
6.3.2	Transpositional Relations for Nonholonomic Systems . . . . .	44
6.4	Remarks . . . . .	44
<b>II</b>	<b>Variational Principles in Constrained Mechanical Systems</b>	<b>45</b>
<b>7</b>	<b>Differential Variational Principles</b>	<b>47</b>
7.1	D'Alembert-Lagrange Principle . . . . .	47
7.1.1	D'Alembert Principle . . . . .	47
7.1.2	Principle of Virtual Displacements . . . . .	47
7.1.3	D'Alembert-Lagrange Principle . . . . .	48
7.1.4	D'Alembert-Lagrange Principle in Terms of Generalized Coordinates . . . . .	48
7.2	Jourdain Principle . . . . .	50
7.2.1	Jourdain Principle . . . . .	50
7.2.2	Jourdain Principle in Terms of Generalized Coordinates . . . . .	50
7.3	Gauss Principle . . . . .	50
7.3.1	Gauss Principle . . . . .	51
7.3.2	Gauss Principle in Terms of Generalized Coordinates . . . . .	51
7.4	Universal D'Alembert Principle . . . . .	51
7.4.1	Universal D'Alembert Principle . . . . .	52
7.4.2	Universal D'Alembert Principle in Terms of Generalized Coordinates . . . . .	52
7.5	Applications of Gauss Principle . . . . .	54
7.5.1	Simple Applications . . . . .	54
7.5.2	Application of Gauss Principle in Robot Dynamics . . . . .	56
7.5.3	Application of Gauss Principle in Study Approximate Solution of Equations of Nonlinear Vibration . . . . .	56
7.6	Remarks . . . . .	58

---

<b>8 Integral Variational Principles in Terms of Generalized Coordinates for Holonomic Systems</b>	<b>59</b>
8.1 Hamilton's Principle . . . . .	59
8.1.1 Hamilton's Principle . . . . .	59
8.1.2 Deduction of Lagrange Equations by Means of Hamilton's Principle . . . . .	62
8.1.3 Character of Extreme of Hamilton's Principle . . . . .	62
8.1.4 Applications in Finding Approximate Solution . . . . .	64
8.1.5 Hamilton's Principle for General Holonomic Systems . . . . .	66
8.2 Lagrange's Principle . . . . .	66
8.2.1 Non-contemporaneous Variation . . . . .	67
8.2.2 Lagrange's Principle . . . . .	67
8.2.3 Other Forms of Lagrange's Principle . . . . .	68
8.2.4 Deduction of Lagrange's Equations by Means of Lagrange's Principle . . . . .	69
8.2.5 Generalization of Lagrange's Principle to Non-conservative Systems and Its Application . . . . .	70
8.3 Remarks . . . . .	72
<b>9 Integral Variational Principles in Terms of Quasi-Coordinates for Holonomic Systems</b>	<b>73</b>
9.1 Hamilton's Principle in Terms of Quasi-Coordinates . . . . .	73
9.1.1 Hamilton's Principle . . . . .	73
9.1.2 Transpositional Relations . . . . .	74
9.1.3 Deduction of Equations of Motion in Terms of Quasi-Coordinates by Means of Hamilton's Principle . . . . .	75
9.1.4 Hamilton's Principle for General Holonomic Systems . . . . .	76
9.2 Lagrange's Principle in Terms of Quasi-Coordinates . . . . .	78
9.2.1 Lagrange's Principle . . . . .	78
9.2.2 Deduction of Equations of Motion in Terms of Quasi-Coordinates by Means of Lagrange's Principle . . . . .	79
9.3 Remarks . . . . .	79
<b>10 Integral Variational Principles for Nonholonomic Systems</b>	<b>81</b>
10.1 Definitions of Variation $\delta q_s$ . . . . .	81
10.1.1 Necessity of Definition of Variation of Generalized Velocities for Nonholo- nomic Systems . . . . .	81
10.1.2 Suslov's Definition . . . . .	82
10.1.3 Hölder's Definition . . . . .	83
10.2 Integral Variational Principles in Terms of Generalized Coordinates for Nonholo- nomic Systems . . . . .	83
10.2.1 Hamilton's Principle for Nonholonomic Systems . . . . .	83
10.2.2 Necessary and Sufficient Condition Under Which Hamilton's Principle for Nonholonomic Systems Is Principle of Stationary Action . . . . .	85
10.2.3 Deduction of Equations of Motion for Nonholonomic Systems by Means of Hamilton's Principle . . . . .	88
10.2.4 General Form of Hamilton's Principle for Nonholonomic Systems . . . . .	89
10.2.5 Lagrange's Principle in Terms of Generalized Coordinates for Nonholonomic Systems . . . . .	90
10.3 Integral Variational Principle in Terms of Quasi- Coordinates for Nonholonomic Systems . . . . .	93

---

10.3.1 Hamilton's Principle in Terms of Quasi-Coordinates . . . . .	93
10.3.2 Lagrange's Principle in Terms of Quasi-Coordinates . . . . .	94
10.4 Remarks . . . . .	94
<b>11 Pfaff-Birkhoff Principle</b>	<b>95</b>
11.1 Statement of Pfaff-Birkhoff Principle . . . . .	95
11.2 Hamilton's Principle as a Particular Case of Pfaff-Birkhoff Principle . . . . .	96
11.3 Birkhoff's Equations . . . . .	97
11.4 Pfaff-Birkhoff-d'Alembert Principle . . . . .	97
11.5 Remarks . . . . .	98
<b>III Differential Equations of Motion of Constrained Mechanical Systems</b>	<b>99</b>
<b>12 Lagrange Equations of Holonomic Systems</b>	<b>101</b>
12.1 Lagrange Equations of Second Kind . . . . .	101
12.2 Lagrange Equations of Systems with Redundant Coordinates . . . . .	107
12.3 Lagrange Equations in Terms of Quasi-Coordinates . . . . .	108
12.4 Lagrange Equations with Dissipative Function . . . . .	111
12.5 Remarks . . . . .	113
<b>13 Lagrange Equations with Multiplier for Nonholonomic Systems</b>	<b>115</b>
13.1 Deduction of Lagrange Equations with Multiplier . . . . .	115
13.2 Determination of Nonholonomic Constraint Forces . . . . .	116
13.3 Remarks . . . . .	118
<b>14 Mac Millan Equations for Nonholonomic Systems</b>	<b>119</b>
14.1 Deduction of Mac Millan Equations . . . . .	119
14.2 Application of Mac Millan Equations . . . . .	120
14.3 Remarks . . . . .	123
<b>15 Volterra Equations for Nonholonomic Systems</b>	<b>125</b>
15.1 Deduction of Generalized Volterra Equations . . . . .	125
15.2 Volterra Equations and Their Equivalent Forms . . . . .	127
15.2.1 Volterra Equations of First Form . . . . .	127
15.2.2 Volterra Equations of Second Form . . . . .	127
15.2.3 Volterra Equations of Third Form . . . . .	128
15.2.4 Volterra Equations of Fourth Form . . . . .	128
15.3 Application of Volterra Equations . . . . .	128
15.4 Remarks . . . . .	129
<b>16 Chaplygin Equations for Nonholonomic Systems</b>	<b>131</b>
16.1 Generalized Chaplygin Equations . . . . .	131
16.2 Voronetz Equations . . . . .	133
16.3 Chaplygin Equations . . . . .	133
16.4 Chaplygin Equations in Terms of Quasi-Coordinates . . . . .	133
16.5 Application of Chaplygin Equations . . . . .	134
16.6 Remarks . . . . .	139

<b>17 Boltzmann-Hamel Equations for Nonholonomic Systems</b>	<b>141</b>
17.1 Deduction of Boltzmann-Hamel Equations . . . . .	141
17.2 Application of Boltzmann-Hamel Equations . . . . .	142
17.3 Remarks . . . . .	147
<b>18 Euler-Lagrange Equations for Higher Order Nonholonomic Systems</b>	<b>149</b>
18.1 Routh Type of Equations . . . . .	149
18.2 Generalized Lagrange Type of Equations . . . . .	149
18.3 Remarks . . . . .	153
<b>19 Nielsen Equations</b>	<b>155</b>
19.1 Nielsen Equations for Holonomic Systems . . . . .	155
19.1.1 Nielsen Equations in Terms of Generalized Coordinates . . . . .	155
19.1.2 Nielsen Equations in Terms of Quasi-Coordinates . . . . .	156
19.2 Nielsen Equations for First Order Nonholonomic Systems . . . . .	159
19.2.1 Nielsen Equations with Multipliers . . . . .	160
19.2.2 Nielsen Natural Equations . . . . .	160
19.2.3 Generalized Nielsen Equations in Terms of Generalized Coordinates . . . . .	161
19.2.4 Generalized Nielsen Equations of First Type in Terms of Quasi-Coordinates . . . . .	161
19.2.5 Generalized Nielsen Equations of Second Type in Terms of Quasi-Coordinates . . . . .	162
19.3 Remarks . . . . .	165
<b>20 Appell Equations</b>	<b>167</b>
20.1 Appell Equations . . . . .	167
20.1.1 Appell Equations for Holonomic Systems . . . . .	167
20.1.2 Constitution of Appell Function . . . . .	170
20.1.3 Appell Equations for First Order Nonholonomic Systems . . . . .	174
20.1.4 Appell Equations for Higher Order Nonholonomic Systems . . . . .	178
20.2 Tzénoff Equations . . . . .	180
20.2.1 Tzénoff Equations for Holonomic Systems . . . . .	180
20.2.2 Tzénoff Equations for First Order Nonholonomic Systems . . . . .	183
20.2.3 Tzénoff Equations for Higher Order Nonholonomic Systems . . . . .	185
20.3 Remarks . . . . .	186
<b>21 Equations of Motion of Mixed Type</b>	<b>187</b>
21.1 Equations of Motion Mixed by Two Types . . . . .	187
21.1.1 Equations of Motion Mixed by Euler-Lagrange Type and Nielsen Type . . . . .	187
21.1.2 Equations of Motion Mixed by Euler-Lagrange Type and Appell Type . . . . .	188
21.1.3 Equations of Motion Mixed by Nielsen Type and Appell Type . . . . .	193
21.2 New Equations of Mixed Type . . . . .	193
21.2.1 New Equations of Mixed Type for Holonomic Systems . . . . .	193
21.2.2 New Equations of Mixed Type for Nonholonomic Systems . . . . .	194
21.3 Remarks . . . . .	196

<b>22 Canonical Equations</b>	<b>197</b>
22.1 Hamilton Equations for Holonomic Systems . . . . .	197
22.1.1 Legendre Transformation . . . . .	197
22.1.2 Canonical Equations of Motion . . . . .	198
22.2 Hamilton Equations for Nonholonomic Systems . . . . .	201
22.2.1 Canonical Form of Routh Equations . . . . .	201
22.2.2 Canonical Form of Chaplygin Equations . . . . .	203
22.2.3 Canonical Form of Boltzmann-Hamel Equations . . . . .	203
22.3 Remarks . . . . .	204
<b>IV Special Problems in Constrained Mechanical Systems</b>	<b>205</b>
<b>23 Stability of Motion and Theory of Small Oscillations</b>	<b>207</b>
23.1 Stability of Equilibrium and Stability of Motion for Holonomic Systems . . . . .	207
23.1.1 Condition of Equilibrium and Stability of Equilibrium . . . . .	207
23.1.2 Concepts and Conclusions about Stability . . . . .	209
23.2 Small Oscillations of Holonomic Systems . . . . .	213
23.2.1 Small Oscillations of Conservative Systems . . . . .	213
23.2.2 Free Vibration and Forced Vibration in Terms of Principal Coordinates . . . . .	215
23.3 Small Vibration Near Equilibrium State and Stability for Nonholonomic Systems . . . . .	217
23.3.1 Small Vibration Near Equilibrium State . . . . .	217
23.3.2 Manifold of Equilibrium State and Its Stability for Nonholonomic Systems . . . . .	218
23.4 Remarks . . . . .	220
<b>24 Dynamics of Rigid Body with Fixed Point</b>	<b>221</b>
24.1 Euler-Poisson Equations and Three Classical Integrable Cases . . . . .	221
24.1.1 Euler-Poisson Equations . . . . .	221
24.1.2 Three First Integrals for Euler-Poisson Equations . . . . .	222
24.1.3 Three Classical Integrable Cases of Euler-Poisson Equations . . . . .	223
24.2 Harlamov Equations and Their Order Reduction . . . . .	223
24.2.1 Equations of Motion in Specific Coordinate System . . . . .	223
24.2.2 Harlamov Equations . . . . .	225
24.2.3 Reducing to An Integro-differential Equation . . . . .	227
24.3 Particular Integrable Cases for Euler-Poisson Equations . . . . .	227
24.3.1 Hess Case (1890) . . . . .	227
24.3.2 Bobylev-Steklov Case (1896) . . . . .	227
24.3.3 Steklov Case (1899) . . . . .	228
24.3.4 Goriachev Case (1899) . . . . .	228
24.3.5 Chaplygin Case (1904) . . . . .	228
24.3.6 Kowalewski Case (1908) . . . . .	229
24.3.7 Goriachev-Chaplygin Case (1900) . . . . .	229
24.3.8 Grioli Case (1947) . . . . .	230
24.3.9 Harlamova Case (1959) . . . . .	230
24.4 Problem of Motion of Rigid Body Around Fixed Point with Nonholonomic Constraints . . . . .	231
24.4.1 Problem of Rotation of Heavy Rigid Body Around Fixed Point with Nonholonomic Constraints . . . . .	231

24.4.2 Motion of Rigid Body When Force Passing Through Fixed Point . . . . .	232
24.5 Remarks . . . . .	232
<b>25 Dynamics of Relative Motion</b>	<b>235</b>
25.1 Dynamics of Relative Motion for Holonomic Systems . . . . .	235
25.1.1 General Form of Differential Equations of Relative Motion of Carried Body	235
25.1.2 Particular Forms of Equations of Relative Motion of Carried Body . . . . .	237
25.1.3 Equations of Energy Variation . . . . .	238
25.1.4 Relative Equilibrium . . . . .	239
25.1.5 Other Forms of Differential Equations of Relative Motion of Carried Body .	240
25.2 Dynamics of Relative Motion for Nonholonomic Systems . . . . .	242
25.2.1 Lagrange Form of Equations of Relative Motion . . . . .	242
25.2.2 Nielsen Form of Equations of Relative Motion . . . . .	243
25.2.3 Appell Form of Equations of Relative Motion . . . . .	243
25.2.4 Equations of Energy Variation . . . . .	243
25.3 Remarks . . . . .	246
<b>26 Dynamics of Controllable Mechanical Systems</b>	<b>247</b>
26.1 Dynamics of Systems with Constraints of Parameters . . . . .	247
26.1.1 Differential Variational Principles for Systems with Constraints of Parameters	247
26.1.2 Differential Equations of Motion for Systems with Constraints of Parameters	248
26.2 Dynamics of Systems with Servo-Constraints . . . . .	252
26.2.1 Classification of Constraints and Application of D'Alembert-Lagrange Principle . . . . .	252
26.2.2 Differential Equations of Motion of Systems with Servo-Constraints . . . . .	254
26.3 Problems of Control over Forced Motion with Constraints . . . . .	257
26.3.1 Fundamental Principle of Problems of Control over Forced Motion with Constraints . . . . .	257
26.3.2 Differential Equations of Motion of Problems of Control over Forced Motion with Constraints . . . . .	257
26.4 Remarks . . . . .	259
<b>27 Dynamics of Impulsive Motion</b>	<b>261</b>
27.1 Case of Known Strike Impulse . . . . .	261
27.1.1 Application of Differential Variational Principles for Impulsive Motion . .	261
27.1.2 Equations of Impulsive Motion for Holonomic Systems . . . . .	262
27.1.3 Energy Considerations . . . . .	265
27.1.4 Equations of Impulsive Motion for Linear Nonholonomic Systems . . . . .	265
27.1.5 Equations of Impulsive Motion for Nonlinear Nonholonomic Systems . . . . .	268
27.2 Case of Instantaneous Exerted Constraints . . . . .	269
27.3 Remarks . . . . .	273
<b>28 Dynamics of Variable Mass Systems</b>	<b>275</b>
28.1 D'Alembert-Lagrange Principle of Variable Mass Systems . . . . .	275
28.1.1 D'Alembert-Lagrange Principle . . . . .	275
28.1.2 D'Alembert-Lagrange Principle in Terms of Solidifying Derivatives and Solidifying Partial Derivatives . . . . .	276
28.1.3 D'Alembert-Lagrange Principle in Terms of Solidifying Partial Derivatives .	278

28.1.4 D'Alembert-Lagrange Principle in Terms of Ordinary Derivatives and Ordinary Partial Derivatives . . . . .	278
28.2 Hamilton Principle of Variable Mass Systems . . . . .	281
28.2.1 General Form of Hamilton Principle . . . . .	281
28.2.2 Hamilton Principle of Holonomic Systems . . . . .	281
28.2.3 Hamilton Principle of Nonholonomic Systems . . . . .	282
28.3 Differential Equations of Motion of Variable Mass Systems . . . . .	283
28.3.1 Differential Equations of Motion for Holonomic Systems . . . . .	283
28.3.2 Differential Equations of Motion for Nonholonomic Systems . . . . .	284
28.4 Remarks . . . . .	290
<b>29 Dynamics of Electromechanical Systems</b>	<b>291</b>
29.1 Fundamental Concepts and Lagrange-Maxwell Equations . . . . .	291
29.1.1 Fundamental Concepts . . . . .	291
29.1.2 Equations of Electric Circuits . . . . .	292
29.1.3 Ponderomotorial forces . . . . .	293
29.1.4 Lagrange-Maxwell Equations . . . . .	294
29.2 Application of Lagrange-Maxwell Equations . . . . .	295
29.2.1 Electromagnetic Suspension of Rigid Body . . . . .	295
29.2.2 Electrostatic Systems . . . . .	298
29.3 Remarks . . . . .	300
<b>30 Dynamics in Event Space</b>	<b>301</b>
30.1 Hamilton Principle in Event Space . . . . .	301
30.1.1 Constraint Equations and Virtual Displacements in Event Space . . . . .	301
30.1.2 Hamilton Principle in Event Space . . . . .	303
30.1.3 D'Alembert-Lagrange Principle in Event Space . . . . .	304
30.2 Equations of Motion in Event Space for Holonomic Systems . . . . .	304
30.2.1 Lagrange Equations . . . . .	304
30.2.2 Nielsen Equations . . . . .	305
30.2.3 Tzénoff Equations . . . . .	305
30.3 Equations of Motion in Event Space for Nonholonomic Systems . . . . .	307
30.3.1 Equations of Euler-Lagrange Form . . . . .	307
30.3.2 Equations of Nielsen Form . . . . .	308
30.3.3 Equations of Tzénoff Form . . . . .	309
30.4 Remarks . . . . .	310
<b>V Integration Methods in Constrained Mechanical Systems</b>	<b>311</b>
<b>31 Methods of Reduction of Order</b>	<b>313</b>
31.1 Cyclic Integral and Generalized Integral of Energy . . . . .	313
31.1.1 First Integral of Equations of Motion . . . . .	313
31.1.2 Cyclic Integral for Holonomic Systems . . . . .	314
31.1.3 Generalized Integral of Energy for Holonomic Systems . . . . .	314
31.1.4 Cyclic Integral for Nonholonomic Systems . . . . .	316
31.1.5 Generalized Integral of Energy for Nonholonomic Systems . . . . .	317
31.2 Routh Equations and Whittaker Equations for Holonomic Systems . . . . .	319
31.2.1 Routh Method of Reduction of Order . . . . .	319
31.2.2 Whittaker Method of Reduction of Order . . . . .	321
31.3 Methods of Reduction of Order for Nonholonomic Systems . . . . .	323

---

31.3.1 Reduction of Order of Chaplygin Equations by Means of Cyclic Integrals . . . . .	323
31.3.2 Generalized Whittaker Equations for Nonholonomic Systems . . . . .	325
31.4 Remarks . . . . .	327
<b>32 Dynamic Algebra and Poisson Method</b>	<b>329</b>
32.1 Algebraic Structure and Poisson Method for Lagrange System and Hamilton System . . . . .	329
32.1.1 Fundamental Concepts of Algebra . . . . .	329
32.1.2 Algebraic Structure of Lagrange System and Hamilton System . . . . .	330
32.1.3 Poisson Theory of Systems . . . . .	332
32.2 Algebraic Structure and Poisson Method for Special Nonholonomic Systems . . . . .	333
32.2.1 Equations of Motion for Special Nonholonomic Systems . . . . .	334
32.2.2 Algebraic Structure for Special Nonholonomic Systems . . . . .	336
32.2.3 Poisson Theory of Systems . . . . .	336
32.3 Algebraic Structure and Poisson Method for Generalized Hamilton System . . . . .	339
32.3.1 Generalized Poisson Bracket . . . . .	339
32.3.2 Equations of Motion of Generalized Hamilton System . . . . .	340
32.3.3 Poisson Theory of Generalized Hamilton System . . . . .	340
32.4 Algebraic Structure and Poisson Method for Autonomous and Semi-autonomous Birkhoff Systems . . . . .	342
32.4.1 Birkhoff Equations . . . . .	342
32.4.2 Algebraic Structure of Autonomous and Semi-autonomous Birkhoff Systems . . . . .	342
32.4.3 Poisson Theory of Systems . . . . .	343
32.5 Algebraic Structure and Poisson Method for General Holonomic Systems . . . . .	345
32.5.1 Contravariant Algebraic Form of Equations of Motion . . . . .	346
32.5.2 Algebraic Structure of Systems . . . . .	346
32.5.3 Poisson Theory of Systems . . . . .	348
32.6 Algebraic Structure and Poisson Method for General Nonholonomic Systems . . . . .	351
32.6.1 Contravariant Algebraic Form of Equations of Motion . . . . .	351
32.6.2 Algebraic Structure of Systems . . . . .	352
32.6.3 Poisson Theory of Systems . . . . .	352
32.7 Algebraic Structure and Poisson Method for General Birkhoff Systems . . . . .	355
32.7.1 Equations of Motion of Systems . . . . .	355
32.7.2 Algebraic Structure of Systems . . . . .	356
32.7.3 Poisson Theory of Systems . . . . .	357
32.8 Remarks . . . . .	357
<b>33 Canonical Transformations</b>	<b>359</b>
33.1 Canonical Transformations and Their Group Properties . . . . .	359
33.1.1 Canonical Transformations . . . . .	359
33.1.2 Group Properties of Canonical Transformation . . . . .	361
33.2 Generating Functions . . . . .	361
33.2.1 Generating Function of First Kind . . . . .	362
33.2.2 Generating Function of Second Kind . . . . .	363
33.2.3 Generating Function of Third Kind . . . . .	363
33.2.4 Generating Function of Fourth Kind . . . . .	364
33.3 Mathieu Transformation and Point Transformation . . . . .	366
33.3.1 Mathieu Transformations . . . . .	366

33.3.2 Point Transformations . . . . .	366
33.4 Infinitesimal Canonical Transformations . . . . .	368
33.5 Examples . . . . .	369
33.6 Remarks . . . . .	371
<b>34 Hamilton-Jacobi Method</b>	<b>373</b>
34.1 Canonical Transformation Reduced to Zero Hamiltonian . . . . .	373
34.1.1 Canonical Transformation Reduced to Zero Hamiltonian . . . . .	373
34.1.2 Canonical Transformation Reduced to Zero and Hamilton-Jacobi Equation . . . . .	374
34.2 Hamilton-Jacobi Theorem . . . . .	376
34.2.1 Hamilton-Jacobi Theorem . . . . .	377
34.2.2 Application of Hamilton-Jacobi Theorem . . . . .	378
34.3 Liouville and Stäckel Cases . . . . .	382
34.3.1 Stäckel theorem . . . . .	382
34.3.2 Liouville Case . . . . .	384
34.4 Application of Hamilton-Jacobi Method to Particular Nonholonomic Systems . . . . .	386
34.4.1 Lagrange Formalization of Equations with Multipliers . . . . .	386
34.4.2 Lagrange Formalization of Chaplygin Systems . . . . .	389
34.5 Remarks . . . . .	391
<b>35 Field Method</b>	<b>393</b>
35.1 Field Method for Solving Ordinary Differential Equations . . . . .	393
35.1.1 Field Method . . . . .	393
35.1.2 Application . . . . .	395
35.2 Field Method for Holonomic Systems . . . . .	396
35.2.1 Standard Form of Equations of Motion for Holonomic Systems . . . . .	396
35.2.2 Application of Field Method . . . . .	396
35.3 Field Method for Nonholonomic Systems . . . . .	398
35.3.1 Standard Form of Routh Equations and Field Method . . . . .	399
35.3.2 Integration of Chaplygin Equations . . . . .	401
35.4 Remarks . . . . .	405
<b>36 Integral Invariants</b>	<b>407</b>
36.1 First Order Linear Relative Integral Invariants of Poincaré . . . . .	407
36.1.1 Sufficient Condition . . . . .	407
36.1.2 Necessary Condition . . . . .	409
36.2 Higher Order Integral Invariants . . . . .	409
36.2.1 Higher Order Integral Invariants . . . . .	409
36.2.2 Liouville Theorem . . . . .	410
36.3 Canonical Transformations and Integral Invariants . . . . .	414
36.4 Uniqueness Theorem on Integral Invariants . . . . .	416
36.5 Poincaré-Cartan Integral Invariants . . . . .	418
36.6 Dynamical Equations Without Integral Invariants . . . . .	419
36.7 Remarks . . . . .	420

<b>VI Symmetries and Conserved Quantities in Constrained Mechanical Systems</b>	<b>421</b>
<b>37 Noether Symmetries and Conserved Quantities</b>	<b>423</b>
37.1 Hamilton Action and Noether Symmetries . . . . .	423
37.1.1 Variation of Hamilton Action . . . . .	423
37.1.2 Symmetrical Transformations, Quasi-Symmetrical Transformations and Generalized Quasi-Symmetrical Transformations . . . . .	424
37.1.3 Killing Equations . . . . .	427
37.2 Noether Theory of Lagrange System . . . . .	430
37.2.1 Equations of Motion of Lagrange System . . . . .	430
37.2.2 Noether Theorem of Lagrange System . . . . .	430
37.2.3 Noether Inverse Theorem of Lagrange System . . . . .	431
37.2.4 Deduction of Basic Conservation Laws in Mechanics . . . . .	432
37.3 Noether Theory of Hamilton System . . . . .	436
37.3.1 Variation of Hamilton Action in Phase Space . . . . .	436
37.3.2 Symmetrical Transformations, Quasi-Symmetrical Transformations and Generalized Quasi-Symmetrical Transformations in Phase Space . . . . .	437
37.3.3 Killing Equations . . . . .	439
37.3.4 Noether Theorem of Hamilton System . . . . .	440
37.3.5 Noether Inverse Theorem of Hamilton System . . . . .	441
37.4 Noether Theory of General Holonomic Systems . . . . .	444
37.4.1 Equations of Motion of Systems . . . . .	445
37.4.2 Generalized Noether Theorem . . . . .	445
37.4.3 Generalized Noether Inverse Theorem . . . . .	445
37.5 Noether Theory of General Nonholonomic Systems . . . . .	450
37.5.1 Equations of Motion for Nonholonomic Systems . . . . .	450
37.5.2 Noether Theory of Corresponding Holonomic Systems . . . . .	451
37.5.3 Generalized Noether Theorem of Nonholonomic Systems . . . . .	452
37.5.4 Generalized Noether Inverse Theorem of Nonholonomic Systems . . . . .	453
37.5.5 Noether Symmetries for Nonholonomic Systems and Corresponding Holonomic Systems . . . . .	453
37.6 Noether Theory of Birkhoff Systems . . . . .	459
37.6.1 Pfaff Action and Noether Symmetries . . . . .	460
37.6.2 Generalized Noether Theorem of Birkhoff Systems . . . . .	464
37.6.3 Generalized Noether Inverse Theorem of Birkhoff Systems . . . . .	465
37.7 Remarks . . . . .	470
<b>38 Lie Symmetries and Hojman Conserved Quantities</b>	<b>471</b>
38.1 Hojman Theorem . . . . .	471
38.2 Lie Symmetries and Hojman Conserved Quantities of Lagrange System . . . . .	473
38.3 Lie Symmetries and Hojman Conserved Quantities of Hamilton System . . . . .	475
38.4 Lie Symmetries and Hojman Conserved Quantities of General Holonomic Systems . . . . .	479
38.5 Lie Symmetries and Hojman Conserved Quantities of General Nonholonomic Systems . . . . .	482
38.5.1 Equations of Motion for Nonholonomic Systems . . . . .	482
38.5.2 Lie Symmetries of Systems . . . . .	483
38.5.3 Generalization of Hojman Theorem . . . . .	483