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Mechanics $v(t) =$
 $dr(t) / dt, (1)$

and the

acceleration

$a(t)$, which is

the time rate of
change of the

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velocity, $a(t) = \frac{dv(t)}{dt}$. (2) It follows from (1) and (2) that the acceleration is also the second derivative $a = \frac{d^2r}{dt^2}$. (3)

Sometimes use is made of Newton's notation, where a dot denotes differentiation with

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Problem 9.1 One

of the attempts

at combining the

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8 Problem 8.4

The Lagrangian

for a system can

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problems. The solution to a given mechanical problem is obtained by solving a set of n second-order differential equations known as Euler-

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equations of
motion, $\frac{d}{dt} L$

$\frac{\partial L}{\partial q_i} = 0:$

(1.4) $\frac{\partial L}{\partial q_i} = 0$

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Thus, the most
general solution
is $s(\varphi) =$

$$s_0 - C \cos(\varphi - \varphi_0) ,$$

(9.42) 150

CHAPTER 9.
CENTRAL FORCES
AND ORBITAL
MECHANICS Figure
9.3: Precession
in a soluble
model, with
geometric orbit
 $r(\varphi) = r_0 / (1$

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$-\epsilon \cos \beta \phi$), shown here with $\beta = 1.1$. Periapsis and apoapsis advance by $\Delta \phi = 2\pi(1 - \beta^{-1})$ per cycle. where C and ϕ_0 are constants.

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Newton's laws,
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