5.1 LINEAR EQUATIONS: INITIAL-VALUE PROBLEMS

• Linear dynamical system • Hooke's law • Newton's second law of motion • Spring/mass system • Free undamped motion • Simple harmonic motion • Equation of motion • Amplitude • Phase angle • Aging spring • Free damped motion • Driven motion • Transient and steady-state terms • Pure resonance • Series circuits

In this section we consider several linear dynamical systems in which each mathematical model is a second-order differential equation with constant coefficients

$$a_2\frac{d^2y}{dt^2} + a_1\frac{dy}{dt} + a_0y = g(t).$$

Recall that the function g is the **input** or **forcing function** of the system. A solution $y(t)$ of the differential equation on an interval containing t_0 and satisfies prescribed initial conditions $y(t_0) = y_0$, $y'(t_0) = y_1$ is the **output** or **response** of the system.

5.1.1 SPRING/MASS SYSTEMS: FREE UNDAMPED MOTION

Hooke's Law Suppose that a flexible spring is suspended vertically from a rigid support and then a mass m is attached to its free end. The amount of stretch, or elongation, of the spring will of course depend on the mass; masses with different weights stretch the spring by differing amounts. By Hooke's law, the spring itself exerts a restoring force F opposite to the direction of elongation and proportional to the amount of elongation s. Simply stated, $F = ks$, where k is a constant of proportionality called the **spring constant.** The spring is essentially characterized by the number k. For example, if a mass weighing 10 pounds stretches a spring $\frac{1}{2}$ foot, then $10 = k(\frac{1}{2})$ implies $k = 20$ lb/ft. Necessarily then, a mass weighing, say, 8 pounds stretches the same spring only $\frac{2}{5}$ foot.

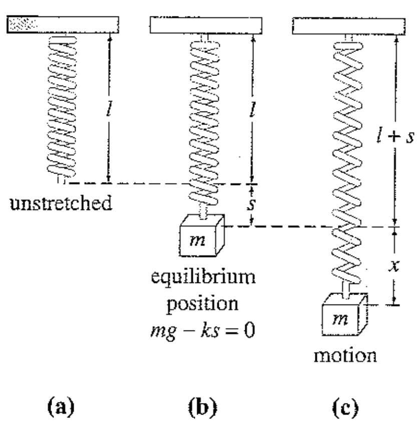


Figure 5.1

Newton's Second Law After a mass m is attached to a spring, it stretches the spring by an amount s and attains a position of equilibrium at which its weight W is balanced by the restoring force ks. Recall that weight is defined by $W = mg$, where mass is measured in slugs, kilograms, or grams and $g = 32$ ft/s^2, 9.8 m/s^2, or 980 cm/s^2, respectively. As indicated in Figure 5.1(b), the condition of equilibrium is $mg = ks$ or $mg - ks = 0$. If the mass is displaced by an amount x from its equilibrium position, the restoring force of the spring is then $k(x + s)$. Assuming that there are no retarding forces acting on the system and assuming that the mass vibrates free of other external forces—**free motion**—we can equate Newton's second law with the net, or resultant, force of the restoring force and the weight:

$$m\frac{d^2x}{dt^2} = -k(s + x) + mg = -kx + \underbrace{mg - ks}_{\text{zero}} = -kx. \tag{1}$$

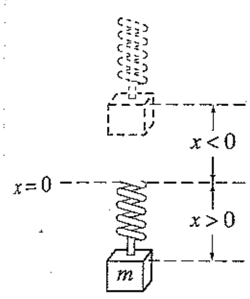


Figure 5.2

The negative sign in (1) indicates that the restoring force of the spring acts opposite to the direction of motion. Furthermore, we can adopt the convention that displacements measured *below* the equilibrium position are positive. See Figure 5.2.

DE of Free Undamped Motion By dividing (1) by the mass m we obtain the second-order differential equation $d^2x/dt^2 + (k/m)x = 0$ or

$$\frac{d^2x}{dt^2} + \omega^2 x = 0, \tag{2}$$

where $\omega^2 = k/m$. Equation (2) is said to describe **simple harmonic motion** or **free undamped motion.** Two obvious initial conditions associated with (2) are $x(0) = x_0$, the amount of initial displacement, and $x'(0) = x_1$, the initial velocity of the mass. For example, if $x_0 > 0$, $x_1 < 0$, the mass starts from a point *below* the equilibrium position with an imparted *upward* velocity. When $x_1 = 0$ the mass is said to be released from *rest.* For example, if $x_0 < 0$, $x_1 = 0$, the mass is released from rest from a point $|x_0|$ units *above* the equilibrium position.

Solution and Equation of Motion To solve equation (2) we note that the solutions of the auxiliary equation $m^2 + \omega^2 = 0$ are the complex numbers $m_1 = \omega i$, $m_2 = -\omega i$. Thus from (8) of Section 4.3 we find the general solution of (2) to be

$$x(t) = c_1 \cos \omega t + c_2 \sin \omega t. \tag{3}$$

The **period** of free vibrations described by (3) is $T = 2\pi/\omega$, and the **frequency** is $f = 1/T = \omega/2\pi$. For example, for $x(t) = 2\cos 3t - 4\sin 3t$ the period is $2\pi/3$ and the frequency is $3/2\pi$. The former number means that the graph of $x(t)$ repeats every $2\pi/3$ units; the latter number means that there are 3 cycles of the graph every 2π units or, equivalently, that the mass undergoes $3/2\pi$ complete vibrations per unit time. In addition, it can be shown that the period $2\pi/\omega$ is the time interval between two successive maxima of $x(t)$. Keep in mind that a maximum of $x(t)$ is a positive displacement corresponding to the mass's attaining a maximum distance *below* the equilibrium position, whereas a minimum of $x(t)$ is a negative displacement corresponding to the mass's attaining a maximum height *above* the equilibrium position. We refer to either case as an **extreme displacement** of the mass. Finally, when the initial conditions are used to determine the constants c_1 and c_2 in (3), we say that the resulting particular solution or response is the **equation of motion.**

EXAMPLE 1 Free Undamped Motion

A mass weighing 2 pounds stretches a spring 6 inches. At $t = 0$ the mass is released from a point 8 inches below the equilibrium position with an upward velocity of $\frac{4}{3}$ ft/s. Determine the equation of free motion.

Solution Because we are using the engineering system of units, the measurements given in terms of inches must be converted into feet: 6 in. = $\frac{1}{2}$ ft; 8 in. = $\frac{2}{3}$ ft. In addition, we must convert the units of weight given in pounds into units of mass. From $m = W/g$ we have $m = \frac{2}{32} = \frac{1}{16}$ slug. Also, from Hooke's law, $2 = k(\frac{1}{2})$ implies that the spring constant is $k = 4$ lb/ft. Hence (1) gives

$$\frac{1}{16}\frac{d^2x}{dt^2} = -4x \quad \text{or} \quad \frac{d^2x}{dt^2} + 64x = 0.$$

The initial displacement and initial velocity are $x(0) = \frac{2}{3}$, $x'(0) = -\frac{4}{3}$, where the negative sign in the last condition is a consequence of the fact that the mass is given an initial velocity in the negative, or upward, direction.

Now $\omega^2 = 64$ or $\omega = 8$, so the general solution of the differential equation is

$$x(t) = c_1 \cos 8t + c_2 \sin 8t. \tag{4}$$

Applying the initial conditions to $x(t)$ and $x'(t)$ gives $c_1 = \frac{2}{3}$ and $c_2 = -\frac{1}{6}$. Thus the equation of motion is

$$x(t) = \frac{2}{3}\cos 8t - \frac{1}{6}\sin 8t. \tag{5}$$

Alternative Form of $x(t)$ When $c_1 \neq 0$ and $c_2 \neq 0$, the actual **amplitude** A of free vibrations is not obvious from inspection of equation (3). For example, although the mass in Example 1 is initially displaced $\frac{2}{3}$ foot beyond the equilibrium position, the amplitude of vibrations is a number larger than $\frac{2}{3}$. Hence it is often convenient to convert a solution of form (3) to the simpler form

$$x(t) = A \sin(\omega t + \phi), \tag{6}$$

where $A = \sqrt{c_1^2 + c_2^2}$ and ϕ is a **phase angle** defined by

$$\left.\begin{aligned} \sin\phi &= \frac{c_1}{A} \\ \cos\phi &= \frac{c_2}{A} \end{aligned}\right\} \tan\phi = \frac{c_1}{c_2}. \tag{7}$$

To verify this we expand (6) by the addition formula for the sine function:

$$A \sin \omega t \cos\phi + A\cos\omega t \sin\phi = (A\sin\phi)\cos\omega t + (A\cos\phi)\sin\omega t. \tag{8}$$

It follows from Figure 5.3 that if ϕ is defined by

$$\sin\phi = \frac{c_1}{\sqrt{c_1^2 + c_2^2}} = \frac{c_1}{A}, \quad \cos\phi = \frac{c_2}{\sqrt{c_1^2 + c_2^2}} = \frac{c_2}{A},$$

then (8) becomes

$$A\frac{c_1}{A}\cos\omega t + A\frac{c_2}{A}\sin\omega t = c_1\cos\omega t + c_2\sin\omega t = x(t).$$

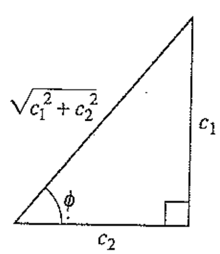


Figure 5.3

EXAMPLE 2 **Alternative Form of Solution (5)**

In view of the foregoing discussion, we can write solution (5), $x(t) = \frac{2}{3}\cos 8t - \frac{1}{6}\sin 8t$, in the alternative form $x(t) = A\sin(8t + \phi)$. Computation of the amplitude is straightforward, $A = \sqrt{(\frac{2}{3})^2 + (-\frac{1}{6})^2} = \sqrt{\frac{17}{36}} \approx 0.69$ ft, but some care should be exercised when computing the phase angle ϕ defined by (7). With $c_1 = \frac{2}{3}$ and $c_2 = -\frac{1}{6}$ we find $\tan \phi = -4$, and a calculator then gives $\tan^{-1}(-4) = -1.326$ rad. This is *not* the phase angle, since $\tan^{-1}(-4)$ is located in the *fourth quadrant* and therefore contradicts the fact that $\sin \phi > 0$ and $\cos \phi < 0$ because $c_1 > 0$ and $c_2 < 0$. Hence we must take ϕ to be the *second-quadrant* angle $\phi = \pi + (-1.326) = 1.816$ rad. Thus we have

$$x(t) = \frac{\sqrt{17}}{6} \sin(8t + 1.816). \tag{9}$$

The period of this function is $T = 2\pi/8 = \pi/4$. ■

Figure 5.4(a) illustrates the mass in Example 2 going through approximately two complete cycles of motion. Reading from left to right, the first five positions (marked with black dots) correspond to the initial position of the mass below the equilibrium position ($x = \frac{2}{3}$), the mass passing through the equilibrium position for the first time heading upward

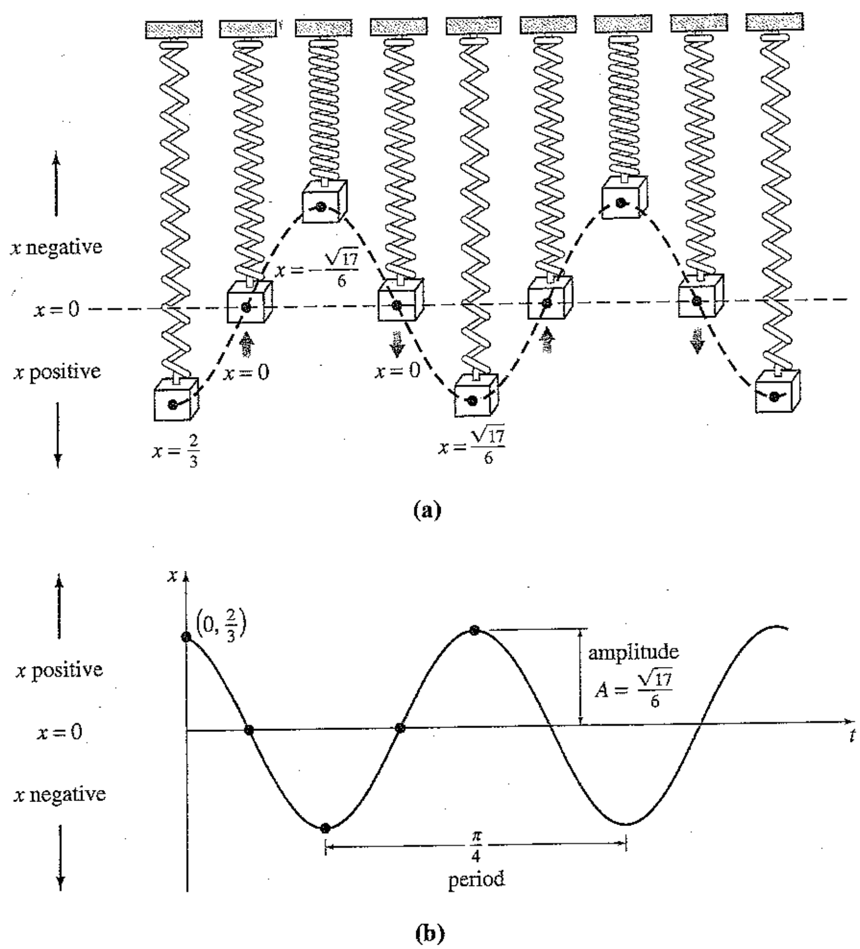


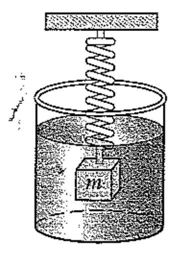
Figure 5.4

($x = 0$), the mass at its extreme displacement above the equilibrium position ($x = -\sqrt{17}/6$), the mass at the equilibrium position for the second time heading downward ($x = 0$), and the mass at its extreme displacement below the equilibrium position ($x = \sqrt{17}/6$). The dots on the graph of (9), given in Figure 5.4(b), also agree with the five positions just given. Note, however, that in Figure 5.4(b) the positive direction in the tx-plane is the usual upward direction and so is opposite to the positive direction indicated in Figure 5.4(a). Hence the solid color graph representing the motion of the mass in Figure 5.4(b) is the mirror image through the t-axis of the black dashed curve in Figure 5.4(a).

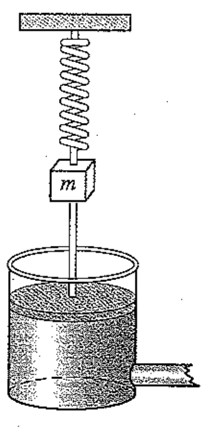
Form (6) is very useful, since it is easy to find values of time for which the graph of $x(t)$ crosses the positive t-axis (the line $x = 0$). We observe that $\sin(\omega t + \phi) = 0$ when $\omega t + \phi = n\pi$, where n is a nonnegative integer.

Systems with Variable Spring Constants In the model discussed above we assumed an ideal world—a world in which the physical characteristics of the spring do not change over time. In the non-ideal world, however, it seems reasonable to expect that when a spring/mass system is in motion for a long period, the spring will weaken; in other words, the "spring constant" will vary—or, more specifically, decay—with time. In one model for the **aging spring** the spring constant k in (1) is replaced by the decreasing function $K(t) = ke^{-\alpha t}$, $k > 0$, $\alpha > 0$. The linear differential equation $mx'' + ke^{-\alpha t}x = 0$ cannot be solved by the methods considered in Chapter 4. Nevertheless, we can obtain two linearly independent solutions using the methods in Chapter 6. See Problem 15 in Exercises 5.1, Example 3 in Section 6.3, and Problems 25 and 26 in Exercises 6.3.

When a spring/mass system is subjected to an environment in which the temperature is rapidly decreasing, it might make sense to replace the constant k with $K(t) = kt$, $k > 0$, a function that increases with time. The resulting model, $mx'' + ktx = 0$, is a form of **Airy's differential equation.** Like the equation for an aging spring, Airy's equation can be solved by the methods of Chapter 6. See Problem 16 in Exercises 5.1, Example 2 in Section 6.1, and Problems 27–29 in Exercises 6.3.



(a)



(b)

Figure 5.5

5.1.2 SPRING/MASS SYSTEMS: FREE DAMPED MOTION

The concept of free harmonic motion is somewhat unrealistic, since the motion described by equation (1) assumes that there are no retarding forces acting on the moving mass. Unless the mass is suspended in a perfect vacuum, there will be at least a resisting force due to the surrounding medium. As Figure 5.5 shows, the mass could be suspended in a viscous medium or connected to a dashpot damping device.

DE of Free Damped Motion In the study of mechanics, damping forces acting on a body are considered to be proportional to a power of the instantaneous velocity. In particular, we shall assume throughout the subsequent discussion that this force is given by a constant multiple of dx/dt. When no other external forces are impressed on the system, it follows from Newton's second law that

$$m\frac{d^2x}{dt^2} = -kx - \beta\frac{dx}{dt}, \tag{10}$$

where β is a positive *damping constant* and the negative sign is a consequence of the fact that the damping force acts in a direction opposite to the motion.

Dividing (10) by the mass m, we find that the differential equation of **free damped motion** is $d^2x/dt^2 + (\beta/m)dx/dt + (k/m)x = 0$ or

$$\frac{d^2x}{dt^2} + 2\lambda\frac{dx}{dt} + \omega^2 x = 0, \tag{11}$$

where

$$2\lambda = \frac{\beta}{m}, \quad \omega^2 = \frac{k}{m}. \tag{12}$$

The symbol 2λ is used only for algebraic convenience since the auxiliary equation is $m^2 + 2\lambda m + \omega^2 = 0$ and the corresponding roots are then

$$m_1 = -\lambda + \sqrt{\lambda^2 - \omega^2}, \quad m_2 = -\lambda - \sqrt{\lambda^2 - \omega^2}.$$

We can now distinguish three possible cases depending on the algebraic sign of $\lambda^2 - \omega^2$. Since each solution contains the *damping factor* $e^{-\lambda t}$, $\lambda > 0$, the displacements of the mass become negligible as time t increases.

Case I: $\lambda^2 - \omega^2 > 0$ In this situation the system is said to be **overdamped** since the damping coefficient β is large when compared to the spring constant k. The corresponding solution of (11) is $x(t) = c_1e^{m_1t} + c_2e^{m_2t}$ or

$$x(t) = e^{-\lambda t}\left(c_1e^{\sqrt{\lambda^2-\omega^2}\,t} + c_2e^{-\sqrt{\lambda^2-\omega^2}\,t}\right). \tag{13}$$

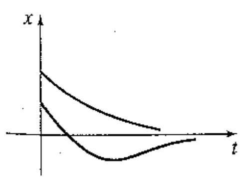


Figure 5.6

This equation represents a smooth and nonoscillatory motion. Figure 5.6 shows two possible graphs of $x(t)$.

Case II: $\lambda^2 - \omega^2 = 0$ The system is said to be **critically damped** since any slight decrease in the damping force would result in oscillatory motion. The general solution of (11) is $x(t) = c_1e^{m_1t} + c_2te^{m_1t}$ or

$$x(t) = e^{-\lambda t}(c_1 + c_2t). \tag{14}$$

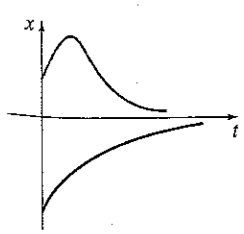


Figure 5.7

Some graphs of typical motion are given in Figure 5.7. Notice that the motion is quite similar to that of an overdamped system. It is also apparent from (14) that the mass can pass through the equilibrium position at most one time.

Case III: $\lambda^2 - \omega^2 < 0$ In this case the system is said to be **underdamped** since the damping coefficient is small compared to the spring constant. The roots m_1 and m_2 are now complex:

$$m_1 = -\lambda + \sqrt{\omega^2 - \lambda^2}\,i, \quad m_2 = -\lambda - \sqrt{\omega^2 - \lambda^2}\,i.$$

Thus the general solution of equation (11) is

$$x(t) = e^{-\lambda t}\left(c_1\cos\sqrt{\omega^2 - \lambda^2}\,t + c_2\sin\sqrt{\omega^2 - \lambda^2}\,t\right). \tag{15}$$

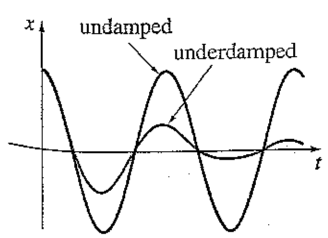


Figure 5.8

As indicated in Figure 5.8, the motion described by (15) is oscillatory; but because of the coefficient $e^{-\lambda t}$, the amplitudes of vibration $\to 0$ as $t \to \infty$.

EXAMPLE 3 Overdamped Motion

It is readily verified that the solution of the initial-value problem

$$\frac{d^2x}{dt^2} + 5\frac{dx}{dt} + 4x = 0, \quad x(0) = 1, \quad x'(0) = 1$$

is

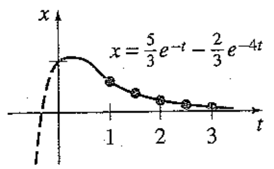
$$x(t) = \frac{5}{3}e^{-t} - \frac{2}{3}e^{-4t}. \tag{16}$$

The problem can be interpreted as representing the overdamped motion of a mass on a spring. The mass starts from a position 1 unit *below* the equilibrium position with a *downward* velocity of 1 ft/s.

To graph $x(t)$ we find the value of t for which the function has an extremum—that is, the value of time for which the first derivative (velocity) is zero. Differentiating (16) gives $x'(t) = -\frac{5}{3}e^{-t} + \frac{8}{3}e^{-4t}$, so that $x'(t) = 0$ implies $e^{3t} = \frac{8}{5}$ or $t = \frac{1}{3}\ln\frac{8}{5} = 0.157$. It follows from the first derivative test, as well as our physical intuition, that $x(0.157) = 1.069$ ft is actually a maximum. In other words, the mass attains an extreme displacement of 1.069 feet below the equilibrium position.

We should also check to see whether the graph crosses the t-axis—that is, whether the mass passes through the equilibrium position. This cannot happen in this instance since the equation $x(t) = 0$, or $e^{3t} = \frac{2}{5}$, has the physically irrelevant solution $t = \frac{1}{3}\ln\frac{2}{5} = -0.305$.

The graph of $x(t)$, along with some other pertinent data, is given in Figure 5.9.



(a)

t	$x(t)$
1	0.601
1.5	0.370
2	0.225
2.5	0.137
3	0.083

(b)

Figure 5.9

EXAMPLE 4 Critically Damped Motion

An 8-pound weight stretches a spring 2 feet. Assuming that a damping force numerically equal to 2 times the instantaneous velocity acts on the system, determine the equation of motion if the weight is released from the equilibrium position with an upward velocity of 3 ft/s.

Solution From Hooke's law we see that $8 = k(2)$ gives $k = 4$ lb/ft and that $W = mg$ gives $m = \frac{8}{32} = \frac{1}{4}$ slug. The differential equation of motion is then

$$\frac{1}{4}\frac{d^2x}{dt^2} = -4x - 2\frac{dx}{dt} \quad \text{or} \quad \frac{d^2x}{dt^2} + 8\frac{dx}{dt} + 16x = 0. \tag{17}$$

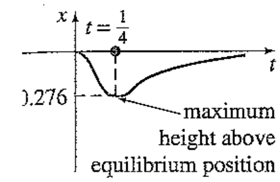
The auxiliary equation for (17) is $m^2 + 8m + 16 = (m + 4)^2 = 0$, so $m_1 = m_2 = -4$. Hence the system is critically damped and

$$x(t) = c_1e^{-4t} + c_2te^{-4t}. \tag{18}$$

Applying the initial conditions $x(0) = 0$ and $x'(0) = -3$, we find, in turn, that $c_1 = 0$ and $c_2 = -3$. Thus the equation of motion is

$$x(t) = -3te^{-4t}. \tag{19}$$

To graph $x(t)$ we proceed as in Example 3. From $x'(t) = -3e^{-4t}(1 - 4t)$ we see that $x'(t) = 0$ when $t = \frac{1}{4}$. The corresponding extreme displacement



ure 5.10

is $x(\frac{1}{4}) = -3(\frac{1}{4})e^{-1} = -0.276$ ft. As shown in Figure 5.10, we interpret this value to mean that the weight reaches a maximum height of 0.276 foot above the equilibrium position.

EXAMPLE 5 Underdamped Motion

A 16-pound weight is attached to a 5-foot-long spring. At equilibrium the spring measures 8.2 feet. If the weight is pushed up and released from rest at a point 2 feet above the equilibrium position, find the displacements $x(t)$ if it is further known that the surrounding medium offers a resistance numerically equal to the instantaneous velocity.

Solution The elongation of the spring after the weight is attached is $8.2 - 5 = 3.2$ ft, so it follows from Hooke's law that $16 = k(3.2)$ or $k = 5$ lb/ft. In addition, $m = \frac{16}{32} = \frac{1}{2}$ slug, so the differential equation is given by

$$\frac{1}{2}\frac{d^2x}{dt^2} = -5x - \frac{dx}{dt} \quad \text{or} \quad \frac{d^2x}{dt^2} + 2\frac{dx}{dt} + 10x = 0. \qquad \textbf{(20)}$$

Proceeding, we find that the roots of $m^2 + 2m + 10 = 0$ are $m_1 = -1 + 3i$ and $m_2 = -1 - 3i$, which then implies that the system is underdamped and

$$x(t) = e^{-t}(c_1 \cos 3t + c_2 \sin 3t). \qquad \textbf{(21)}$$

Finally, the initial conditions $x(0) = -2$ and $x'(0) = 0$ yield $c_1 = -2$ and $c_2 = -\frac{2}{3}$, so the equation of motion is

$$x(t) = e^{-t}\left(-2\cos 3t - \frac{2}{3}\sin 3t\right). \qquad \textbf{(22)}$$

Alternative Form of $x(t)$ In a manner identical to the procedure used on page 218, we can write any solution

$$x(t) = e^{-\lambda t}(c_1 \cos \sqrt{\omega^2 - \lambda^2}t + c_2 \sin \sqrt{\omega^2 - \lambda^2}t)$$

in the alternative form

$$x(t) = Ae^{-\lambda t}\sin(\sqrt{\omega^2 - \lambda^2}t + \phi), \qquad \textbf{(23)}$$

where $A = \sqrt{c_1^2 + c_2^2}$ and the phase angle ϕ is determined from the equations

$$\sin\phi = \frac{c_1}{A}, \quad \cos\phi = \frac{c_2}{A}, \quad \tan\phi = \frac{c_1}{c_2}.$$

The coefficient $Ae^{-\lambda t}$ is sometimes called the **damped amplitude** of vibrations. Because (23) is not a periodic function, the number $2\pi/\sqrt{\omega^2 - \lambda^2}$ is called the **quasi period** and $\sqrt{\omega^2 - \lambda^2}/2\pi$ is the **quasi frequency.** The quasi period is the time interval between two successive maxima of $x(t)$. You should verify, for the equation of motion in Example 5, that $A = 2\sqrt{10}/3$ and $\phi = 4.391$. Therefore an equivalent form of (22) is

$$x(t) = \frac{2\sqrt{10}}{3}e^{-t}\sin(3t + 4.391).$$

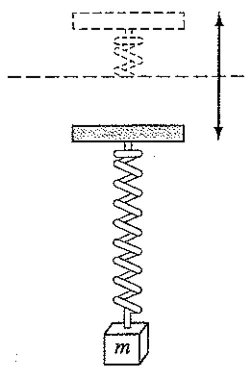


Figure 5.11

5.1.3 SPRING/MASS SYSTEMS: DRIVEN MOTION

DE of Driven Motion with Damping Suppose we now take into consideration an external force $f(t)$ acting on a vibrating mass on a spring. For example, $f(t)$ could represent a driving force causing an oscillatory vertical motion of the support of the spring. See Figure 5.11. The inclusion of $f(t)$ in the formulation of Newton's second law gives the differential equation of **driven** or **forced motion:**

$$m\frac{d^2x}{dt^2} = -kx - \beta\frac{dx}{dt} + f(t). \tag{24}$$

Dividing (24) by m gives

$$\frac{d^2x}{dt^2} + 2\lambda\frac{dx}{dt} + \omega^2 x = F(t), \tag{25}$$

where $F(t) = f(t)/m$ and, as in the preceding section, $2\lambda = \beta/m$, $\omega^2 = k/m$. To solve the latter nonhomogeneous equation we can use either the method of undetermined coefficients or variation of parameters.

EXAMPLE 6 Interpretation of an Initial-Value Problem

Interpret and solve the initial-value problem

$$\frac{1}{5}\frac{d^2x}{dt^2} + 1.2\frac{dx}{dt} + 2x = 5\cos 4t, \quad x(0) = \frac{1}{2}, \quad x'(0) = 0. \tag{26}$$

Solution We can interpret the problem to represent a vibrational system consisting of a mass ($m = \frac{1}{5}$ slug or kilogram) attached to a spring ($k = 2$ lb/ft or N/m). The mass is released from rest $\frac{1}{2}$ unit (foot or meter) below the equilibrium position. The motion is damped ($\beta = 1.2$) and is being driven by an external periodic ($T = \pi/2$ s) force beginning at $t = 0$. Intuitively we would expect that even with damping the system would remain in motion until such time as the forcing function was "turned off," in which case the amplitudes would diminish. However, as the problem is given, $f(t) = 5\cos 4t$ will remain "on" forever.

We first multiply the differential equation in (26) by 5 and solve

$$\frac{dx^2}{dt^2} + 6\frac{dx}{dt} + 10x = 0$$

by the usual methods. Since $m_1 = -3 + i$, $m_2 = -3 - i$, it follows that $x_c(t) = e^{-3t}(c_1 \cos t + c_2 \sin t)$. Using the method of undetermined coefficients, we assume a particular solution of the form $x_p(t) = A\cos 4t + B\sin 4t$. Differentiating $x_p(t)$ and substituting into the DE gives

$$x_p'' + 6x_p' + 10x_p = (-6A + 24B)\cos 4t + (-24A - 6B)\sin 4t = 25\cos 4t$$

The resulting system of equations

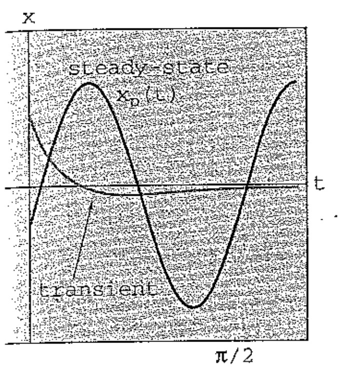
$$-6A + 24B = 25, \quad -24A - 6B = 0$$

yields $A = -\frac{25}{102}$ and $B = \frac{50}{51}$. It follows that

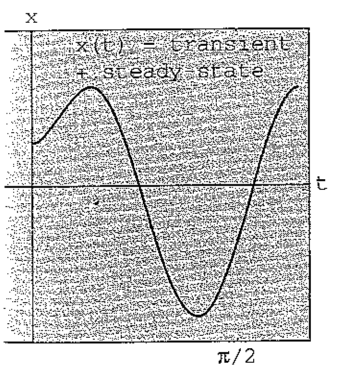
$$x(t) = e^{-3t}(c_1\cos t + c_2\sin t) - \frac{25}{102}\cos 4t + \frac{50}{51}\sin 4t. \tag{27}$$

When we set $t = 0$ in the above equation, we obtain $c_1 = \frac{38}{51}$. By differentiating the expression and then setting $t = 0$, we also find that $c_2 = -\frac{86}{51}$. Therefore the equation of motion is

$$x(t) = e^{-3t}\left(\frac{38}{51}\cos t - \frac{86}{51}\sin t\right) - \frac{25}{102}\cos 4t + \frac{50}{51}\sin 4t. \quad \textbf{(28)}$$



(a)



(b)

ure 5.12

Transient and Steady-State Terms When F is a periodic function, such as $F(t) = F_0 \sin \gamma t$ or $F(t) = F_0 \cos \gamma t$, the general solution of (25) for $\lambda > 0$ is the sum of a nonperiodic function $x_c(t)$ and a periodic function $x_p(t)$. Moreover, $x_c(t)$ dies off as time increases—that is, $\lim_{t\to\infty} x_c(t) = 0$. Thus for large values of time, the displacements of the mass are closely approximated by the particular solution $x_p(t)$. The complementary function $x_c(t)$ is said to be a **transient term** or **transient solution,** and the function $x_p(t)$, the part of the solution that remains after an interval of time, is called a **steady-state term** or **steady-state solution.** Note therefore that the effect of the initial conditions on a spring/mass system driven by F is transient. In the particular solution (28), $e^{-3t}(\frac{38}{51}\cos t - \frac{86}{51}\sin t)$ is a transient term and $x_p(t) = -\frac{25}{102}\cos 4t + \frac{50}{51}\sin 4t$ is a steady-state term. The graphs of these two terms and the solution (28) are given in Figures 5.12(a) and (b), respectively.

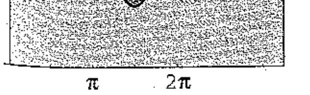
EXAMPLE 7 Transient/Steady-State Solutions

The solution of the initial-value problem

$$\frac{d^2x}{dt^2} + 2\frac{dx}{dt} + 2x = 4\cos t + 2\sin t, \quad x(0) = 0, \quad x'(0) = x_1,$$

where x_1 is constant, is given by

$$x(t) = \underbrace{(x_1 - 2)e^{-t}\sin t}_{\text{transient}} + \underbrace{2\sin t}_{\text{steady-state}}.$$



ure 5.13

Solution curves for selected values of the initial velocity x_1 are shown in Figure 5.13. The graphs show that the influence of the transient term is negligible for about $t > 3\pi/2$.

DE of Driven Motion Without Damping With a periodic impressed force and no damping force, there is no transient term in the solution of a problem. Also, we shall see that a periodic impressed force with a frequency near or the same as the frequency of free undamped vibrations can cause a severe problem in any oscillatory mechanical system.

EXAMPLE 8 Undamped Forced Motion

Solve the initial-value problem

$$\frac{d^2x}{dt^2} + \omega^2 x = F_0 \sin \gamma t, \quad x(0) = 0, \quad x'(0) = 0, \quad \textbf{(29)}$$

where F_0 is a constant and $\gamma \neq \omega$.

Solution The complementary function is $x_c(t) = c_1 \cos \omega t + c_2 \sin \omega t$. To obtain a particular solution we assume $x_p(t) = A \cos \gamma t + B \sin \gamma t$ so that

$$x_p'' + \omega^2 x_p = A(\omega^2 - \gamma^2)\cos \gamma t + B(\omega^2 - \gamma^2)\sin \gamma t = F_0 \sin \gamma t.$$

Equating coefficients immediately gives $A = 0$ and $B = F_0/(\omega^2 - \gamma^2)$. Therefore

$$x_p(t) = \frac{F_0}{\omega^2 - \gamma^2}\sin \gamma t.$$

Applying the given initial conditions to the general solution

$$x(t) = c_1 \cos \omega t + c_2 \sin \omega t + \frac{F_0}{\omega^2 - \gamma^2}\sin \gamma t$$

yields $c_1 = 0$ and $c_2 = -\gamma F_0/\omega(\omega^2 - \gamma^2)$. Thus the solution is

$$x(t) = \frac{F_0}{\omega(\omega^2 - \gamma^2)}(-\gamma \sin \omega t + \omega \sin \gamma t), \quad \gamma \neq \omega. \qquad (30)$$

Pure Resonance Although equation (30) is not defined for $\gamma = \omega$, it is interesting to observe that its limiting value as $\gamma \to \omega$ can be obtained by applying L'Hôpital's rule. This limiting process is analogous to "tuning in" the frequency of the driving force $(\gamma/2\pi)$ to the frequency of free vibrations $(\omega/2\pi)$. Intuitively we expect that over a length of time we should be able to substantially increase the amplitudes of vibration. For $\gamma = \omega$ we define the solution to be

$$\begin{aligned} x(t) = \lim_{\gamma \to \omega} F_0 \frac{-\gamma \sin \omega t + \omega \sin \gamma t}{\omega(\omega^2 - \gamma^2)} &= F_0 \lim_{\gamma \to \omega} \frac{\dfrac{d}{d\gamma}(-\gamma \sin \omega t + \omega \sin \gamma t)}{\dfrac{d}{d\gamma}(\omega^3 - \omega\gamma^2)} \\ &= F_0 \lim_{\gamma \to \omega} \frac{-\sin \omega t + \omega t \cos \gamma t}{-2\omega\gamma} \\ &= F_0 \frac{-\sin \omega t + \omega t \cos \omega t}{-2\omega^2} \\ &= \frac{F_0}{2\omega^2}\sin \omega t - \frac{F_0}{2\omega} t \cos \omega t. \qquad (31) \end{aligned}$$

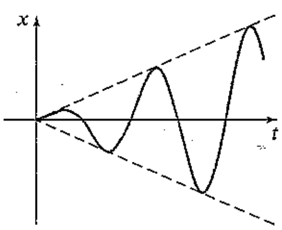


Figure 5.14

As suspected, when $t \to \infty$ the displacements become large; in fact, $|x(t_n)| \to \infty$ when $t_n = n\pi/\omega$, $n = 1, 2, \ldots$. The phenomenon we have just described is known as **pure resonance.** The graph given in Figure 5.14 shows typical motion in this case.

In conclusion it should be noted that there is no actual need to use a limiting process on (30) to obtain the solution for $\gamma = \omega$. Alternatively, equation (31) follows by solving the initial-value problem

$$\frac{d^2x}{dt^2} + \omega^2 x = F_0 \sin \omega t, \quad x(0) = 0, \quad x'(0) = 0$$

directly by conventional methods.

If the displacements of a spring/mass system were actually described by a function such as (31), the system would necessarily fail. Large oscillations of the mass would eventually force the spring beyond its elastic limit. One might argue too that the resonating model presented in Figure 5.14

is completely unrealistic, because it ignores the retarding effects of ever-present damping forces. Although it is true that pure resonance cannot occur when the smallest amount of damping is taken into consideration, large and equally destructive amplitudes of vibration (although bounded as $t \to \infty$) can occur. See Problem 43 in Exercises 5.1.

5.1.4 SERIES CIRCUIT ANALOGUE

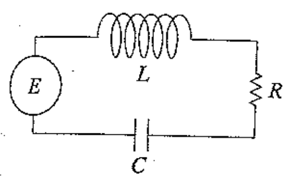


Figure 5.15

***LRC* Series Circuits** As mentioned in the introduction to this chapter, many different physical systems can be described by a linear second-order differential equation similar to the differential equation of forced motion with damping:

$$m\frac{d^2x}{dt^2} + \beta\frac{dx}{dt} + kx = f(t). \tag{32}$$

If $i(t)$ denotes current in the ***LRC* series electrical circuit** shown in Figure 5.15, then the voltage drops across the inductor, resistor, and capacitor are as shown in Figure 1.18. By Kirchhoff's second law, the sum of these voltages equals the voltage $E(t)$ impressed on the circuit; that is,

$$L\frac{di}{dt} + Ri + \frac{1}{C}q = E(t). \tag{33}$$

But the charge $q(t)$ on the capacitor is related to the current $i(t)$ by $i = dq/dt$, and so (33) becomes the linear second-order differential equation

$$L\frac{d^2q}{dt^2} + R\frac{dq}{dt} + \frac{1}{C}q = E(t). \tag{34}$$

The nomenclature used in the analysis of circuits is similar to that used to describe spring-mass systems.

If $E(t) = 0$, the **electrical vibrations** of the circuit are said to be **free.** Since the auxiliary equation for (34) is $Lm^2 + Rm + 1/C = 0$, there will be three forms of the solution with $R \neq 0$, depending on the value of the discriminant $R^2 - 4L/C$. We say that the circuit is

overdamped if $R^2 - 4L/C > 0$,

critically damped if $R^2 - 4L/C = 0$,

and **underdamped** if $R^2 - 4L/C < 0$.

In each of these three cases the general solution of (34) contains the factor $e^{-Rt/2L}$, and so $q(t) \to 0$ as $t \to \infty$. In the underdamped case when $q(0) = q_0$, the charge on the capacitor oscillates as it decays; in other words, the capacitor is charging and discharging as $t \to \infty$. When $E(t) = 0$ and $R = 0$, the circuit is said to be undamped and the electrical vibrations do not approach zero as t increases without bound; the response of the circuit is **simple harmonic.**

EXAMPLE 9 Underdamped Series Circuit

Find the charge $q(t)$ on the capacitor in an LRC series circuit when $L = 0.25$ henry (h), $R = 10$ ohms (Ω), $C = 0.001$ farad (f), $E(t) = 0$, $q(0) = q_0$ coulombs (C), and $i(0) = 0$.

Solution Since $1/C = 1000$, equation (34) becomes

$$\frac{1}{4}q'' + 10q' + 1000q = 0 \quad \text{or} \quad q'' + 40q' + 4000q = 0.$$

Solving this homogeneous equation in the usual manner, we find that the circuit is underdamped and $q(t) = e^{-20t}(c_1 \cos 60t + c_2 \sin 60t)$. Applying the initial conditions, we find $c_1 = q_0$ and $c_2 = \frac{1}{3}q_0$. Thus

$$q(t) = q_0 e^{-20t}\left(\cos 60t + \frac{1}{3}\sin 60t\right).$$

Using (23), we can write the foregoing solution as

$$q(t) = \frac{q_0\sqrt{10}}{3}e^{-20t}\sin(60t + 1.249).$$

When there is an impressed voltage $E(t)$ on the circuit, the electrical vibrations are said to be **forced.** In the case when $R \neq 0$, the complementary function $q_c(t)$ of (34) is called a **transient solution.** If $E(t)$ is periodic or a constant, then the particular solution $q_p(t)$ of (34) is a **steady-state solution.**

EXAMPLE 10 Steady-State Current

Find the steady-state solution $q_p(t)$ and the **steady-state current** in an LRC series circuit when the impressed voltage is $E(t) = E_0 \sin \gamma t$.

Solution The steady-state solution $q_p(t)$ is a particular solution of the differential equation

$$L\frac{d^2q}{dt^2} + R\frac{dq}{dt} + \frac{1}{C}q = E_0 \sin \gamma t.$$

Using the method of undetermined coefficients, we assume a particular solution of the form $q_p(t) = A \sin \gamma t + B \cos \gamma t$. Substituting this expression into the differential equation, simplifying, and equating coefficients gives

$$A = \frac{E_0\left(L\gamma - \dfrac{1}{C\gamma}\right)}{-\gamma\left(L^2\gamma^2 - \dfrac{2L}{C} + \dfrac{1}{C^2\gamma^2} + R^2\right)}, \quad B = \frac{E_0 R}{-\gamma\left(L^2\gamma^2 - \dfrac{2L}{C} + \dfrac{1}{C^2\gamma^2} + R^2\right)}.$$

It is convenient to express A and B in terms of some new symbols.

If $\quad X = L\gamma - \dfrac{1}{C\gamma}, \quad$ then $\quad X^2 = L^2\gamma^2 - \dfrac{2L}{C} + \dfrac{1}{C^2\gamma^2}.$

If $\quad Z = \sqrt{X^2 + R^2}, \quad$ then $\quad Z^2 = L^2\gamma^2 - \dfrac{2L}{C} + \dfrac{1}{C^2\gamma^2} + R^2.$

Therefore $A = E_0X/(-\gamma Z^2)$ and $B = E_0R/(-\gamma Z^2)$, so the steady-state charge is

$$q_p(t) = -\frac{E_0X}{\gamma Z^2}\sin \gamma t - \frac{E_0R}{\gamma Z^2}\cos \gamma t.$$

Now the steady-state current is given by $i_p(t) = q_p'(t)$:

$$i_p(t) = \frac{E_0}{Z}\left(\frac{R}{Z}\sin\gamma t - \frac{X}{Z}\cos\gamma t\right). \qquad (35)$$

The quantities $X = L\gamma - 1/C\gamma$ and $Z = \sqrt{X^2 + R^2}$ defined in Example 11 are called, respectively, the **reactance** and **impedance** of the circuit. Both the reactance and the impedance are measured in ohms.

EXERCISES 5.1

Answers to odd-numbered problems begin on page AN-5.

5.1.1 Spring/Mass Systems: Free Undamped Motion

1. A 4-pound weight is attached to a spring whose spring constant is 16 lb/ft. What is the period of simple harmonic motion?

2. A 20-kilogram mass is attached to a spring. If the frequency of simple harmonic motion is $2/\pi$ vibrations/second, what is the spring constant k? What is the frequency of simple harmonic motion if the original mass is replaced with an 80-kilogram mass?

3. A 24-pound weight, attached to the end of a spring, stretches it 4 inches. Find the equation of motion if the weight is released from rest from a point 3 inches above the equilibrium position.

4. Determine the equation of motion if the weight in Problem 3 is released from the equilibrium position with an initial downward velocity of 2 ft/s.

5. A 20-pound weight stretches a spring 6 inches. The weight is released from rest 6 inches below the equilibrium position.

(a) Find the position of the weight at $t = \pi/12, \pi/8, \pi/6, \pi/4$, and $9\pi/32$ s.

(b) What is the velocity of the weight when $t = 3\pi/16$ s? In which direction is the weight heading at this instant?

(c) At what times does the weight pass through the equilibrium position?

6. A force of 400 newtons stretches a spring 2 meters. A mass of 50 kilograms is attached to the end of the spring and released from the equilibrium position with an upward velocity of 10 m/s. Find the equation of motion.

7. Another spring whose constant is 20 N/m is suspended from the same rigid support but parallel to the spring/mass system in Problem 6. A mass of 20 kilograms is attached to the second spring, and both masses are released from the equilibrium position with an upward velocity of 10 m/s.

(a) Which mass exhibits the greater amplitude of motion?

(b) Which mass is moving faster at $t = \pi/4$ s? at $\pi/2$ s?

(c) At what times are the two masses in the same position? Where are the masses at these times? In which directions are they moving?

8. A 32-pound weight stretches a spring 2 feet. Determine the amplitude and period of motion if the weight is released 1 foot above the equilibrium position with an initial upward velocity of 2 ft/s. How many complete vibrations will the weight have completed at the end of 4π seconds?

9. An 8-pound weight attached to a spring exhibits simple harmonic motion. Determine the equation of motion if the spring constant is 1 lb/ft and if the weight is released 6 inches below the equilibrium position with a downward velocity of $\frac{3}{2}$ ft/s. Express the solution in form (6).

10. A mass weighing 10 pounds stretches a spring $\frac{1}{4}$ foot. This mass is removed and replaced with a mass of 1.6 slugs, which is released $\frac{1}{3}$ foot above the equilibrium position with a downward velocity of $\frac{5}{4}$ ft/s. Express the solution in form (6). At what times does the mass attain a displacement below the equilibrium position numerically equal to $\frac{1}{2}$ the amplitude?

11. A 64-pound weight attached to the end of a spring stretches it 0.32 foot. From a position 8 inches above the equilibrium position the weight is given a downward velocity of 5 ft/s.

(a) Find the equation of motion.

(b) What are the amplitude and period of motion?

(c) How many complete vibrations will the weight have completed at the end of 3π seconds?

(d) At what time does the weight pass through the equilibrium position heading downward for the second time?

(e) At what time does the weight attain its extreme displacement on either side of the equilibrium position?

(f) What is the position of the weight at $t = 3$ s?

(g) What is the instantaneous velocity at $t = 3$ s?

(h) What is the acceleration at $t = 3$ s?

(i) What is the instantaneous velocity at the times when the weight passes through the equilibrium position?

(j) At what times is the weight 5 inches below the equilibrium position?

(k) At what times is the weight 5 inches below the equilibrium position heading in the upward direction?

12. A mass of 1 slug is suspended from a spring whose characteristic spring constant is 9 lb/ft. Initially the mass starts from a point 1 foot above the equilibrium position with an upward velocity of $\sqrt{3}$ ft/s. Find the times for which the mass is heading downward at a velocity of 3 ft/s.

13. Under some circumstances when two parallel springs, with constants k_1 and k_2, support a single weight W, the **effective spring constant** of the system is given by $k = 4k_1k_2/(k_1 + k_2)$. A 20-pound weight stretches one spring 6 inches and another spring 2 inches. The springs are attached to a common rigid support and then to a metal plate. As

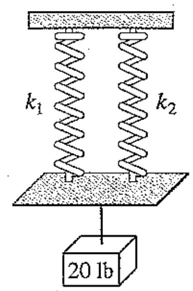


Figure 5.16

shown in Figure 5.16, the 20-pound weight is attached to the center of the plate in the double-spring arrangement. Determine the effective spring constant of this system. Find the equation of motion if the weight is released from the equilibrium position with a downward velocity of 2 ft/s.

14. A certain weight stretches one spring $\frac{1}{3}$ foot and another spring $\frac{1}{2}$ foot. The two springs are attached to a common rigid support in the manner indicated in Problem 13 and Figure 5.16. The first weight is set aside, an 8-pound weight is attached to the double-spring arrangement, and the system is set in motion. If the period of motion is $\pi/15$ second, determine the numerical value of the first weight.

15. By inspection of the differential equation only, discuss the behavior of a spring/mass system described by $4x'' + e^{-0.1t}x = 0$ over a long period of time.

16. By inspection of the differential equation only, discuss the behavior of a spring/mass system described by $4x'' + tx = 0$ over a long period of time.

5.1.2 Spring/Mass Systems: Free Damped Motion

In Problems 17–20 the given figure represents the graph of an equation of motion for a mass on a spring. The spring/mass system is damped. Use the graph to determine

(a) whether the initial displacement of the mass is above or below the equilibrium position and

(b) whether the mass is initially released from rest, heading downward, or heading upward.

17.

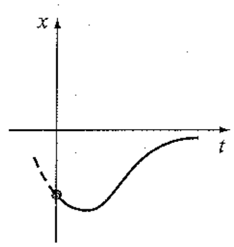


Figure 5.17

18.

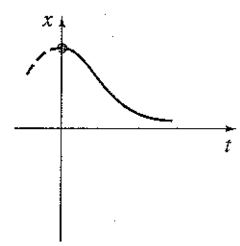


Figure 5.18

19.

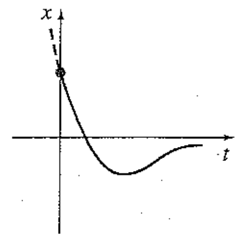


Figure 5.19

20.

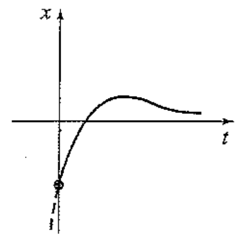


Figure 5.20

21. A 4-pound weight is attached to a spring whose constant is 2 lb/ft. The medium offers a resistance to the motion of the weight numerically equal to the instantaneous velocity. If the weight is released from a point 1 foot above the equilibrium position with a downward velocity of 8 ft/s, determine the time at which the weight passes through the equilibrium position. Find the time at which the weight attains its extreme displacement from the equilibrium position. What is the position of the weight at this instant?

22. A 4-foot spring measures 8 feet long after an 8-pound weight is attached to it. The medium through which the weight moves offers a resistance numerically equal to $\sqrt{2}$ times the instantaneous velocity. Find the equation of motion if the weight is released from the equilibrium position with a downward velocity of 5 ft/s. Find the time at which the weight attains its extreme displacement from the equilibrium position. What is the position of the weight at this instant?

23. A 1-kilogram mass is attached to a spring whose constant is 16 N/m, and the entire system is then submerged in a liquid that imparts a damping force numerically equal to 10 times the instantaneous velocity. Determine the equations of motion if

(a) the weight is released from rest 1 meter below the equilibrium position and

(b) the weight is released 1 meter below the equilibrium position with an upward velocity of 12 m/s.

24. In parts (a) and (b) of Problem 23 determine whether the weight passes through the equilibrium position. In each case find the time at which the weight attains its extreme displacement from the equilibrium position. What is the position of the weight at this instant?

25. A force of 2 pounds stretches a spring 1 foot. A 3.2-pound weight is attached to the spring, and the system is then immersed in a medium that imparts a damping force numerically equal to 0.4 times the instantaneous velocity.

(a) Find the equation of motion if the weight is released from rest 1 foot above the equilibrium position.

(b) Express the equation of motion in the form given in (23).

(c) Find the first time at which the weight passes through the equilibrium position heading upward.

26. After a 10-pound weight is attached to a 5-foot spring, the spring measures 7 feet long. The 10-pound weight is removed and replaced with an 8-pound weight, and the entire system is placed in a medium offering a resistance numerically equal to the instantaneous velocity.

(a) Find the equation of motion if the weight is released $\frac{1}{2}$ foot below the equilibrium position with a downward velocity of 1 ft/s.
(b) Express the equation of motion in the form given in (23).
(c) Find the times at which the weight passes through the equilibrium position heading downward.
(d) Graph the equation of motion.

27. A 10-pound weight attached to a spring stretches it 2 feet. The weight is attached to a dashpot damping device that offers a resistance numerically equal to β ($\beta > 0$) times the instantaneous velocity. Determine the values of the damping constant β so that the subsequent motion is **(a)** overdamped, **(b)** critically damped, and **(c)** underdamped.

28. A 24-pound weight stretches a spring 4 feet. The subsequent motion takes place in a medium offering a resistance numerically equal to β ($\beta > 0$) times the instantaneous velocity. If the weight starts from the equilibrium position with an upward velocity of 2 ft/s, show that if $\beta > 3\sqrt{2}$ the equation of motion is

$$x(t) = \frac{-3}{\sqrt{\beta^2 - 18}} e^{-2\beta t/3} \sinh \frac{2}{3}\sqrt{\beta^2 - 18}\,t.$$

5.1.3 Spring/Mass Systems: Driven Motion

29. A 16-pound weight stretches a spring $\frac{8}{3}$ feet. Initially the weight starts from rest 2 feet below the equilibrium position, and the subsequent motion takes place in a medium that offers a damping force numerically equal to $\frac{1}{2}$ the instantaneous velocity. Find the equation of motion if the weight is driven by an external force equal to $f(t) = 10 \cos 3t$.

30. A mass of 1 slug is attached to a spring whose constant is 5 lb/ft. Initially the mass is released 1 foot below the equilibrium position with a downward velocity of 5 ft/s, and the subsequent motion takes place in a medium that offers a damping force numerically equal to 2 times the instantaneous velocity.
(a) Find the equation of motion if the mass is driven by an external force equal to $f(t) = 12 \cos 2t + 3 \sin 2t$.
(b) Graph the transient and steady-state solutions on the same coordinate axes.
(c) Graph the equation of motion.

31. A mass of 1 slug, when attached to a spring, stretches it 2 feet and then comes to rest in the equilibrium position. Starting at $t = 0$, an external force equal to $f(t) = 8 \sin 4t$ is applied to the system. Find the equation of motion if the surrounding medium offers a damping force numerically equal to 8 times the instantaneous velocity.

32. In Problem 31 determine the equation of motion if the external force is $f(t) = e^{-t} \sin 4t$. Analyze the displacements for $t \to \infty$.

33. When a mass of 2 kilograms is attached to a spring whose constant is 32 N/m, it comes to rest in the equilibrium position. Starting at $t = 0$, a force equal to $f(t) = 68e^{-2t} \cos 4t$ is applied to the system. Find the equation of motion in the absence of damping.

34. In Problem 33 write the equation of motion in the form $x(t) = A \sin(\omega t + \phi) + Be^{-2t} \sin(4t + \theta)$. What is the amplitude of vibrations after a very long time?

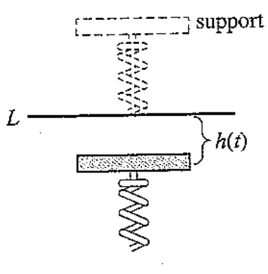


Figure 5.21

35. A mass m is attached to the end of a spring whose constant is k. After the mass reaches equilibrium, its support begins to oscillate vertically about a horizontal line L according to a formula $h(t)$. The value of h represents the distance in feet measured from L. See Figure 5.21.

(a) Determine the differential equation of motion if the entire system moves through a medium offering a damping force numerically equal to $\beta(dx/dt)$.

(b) Solve the differential equation in part (a) if the spring is stretched 4 feet by a weight of 16 pounds and $\beta = 2$, $h(t) = 5\cos t$, $x(0) = x'(0) = 0$.

36. A mass of 100 grams is attached to a spring whose constant is 1600 dynes/cm. After the mass reaches equilibrium, its support oscillates according to the formula $h(t) = \sin 8t$, where h represents displacement from its original position. See Problem 35 and Figure 5.21.

(a) In the absence of damping, determine the equation of motion if the mass starts from rest from the equilibrium position.

(b) At what times does the mass pass through the equilibrium position?

(c) At what times does the mass attain its extreme displacements?

(d) What are the maximum and minimum displacements?

(e) Graph the equation of motion.

In Problems 37 and 38 solve the given initial-value problem.

37. $\dfrac{d^2x}{dt^2} + 4x = -5\sin 2t + 3\cos 2t$, $x(0) = -1$, $x'(0) = 1$

38. $\dfrac{d^2x}{dt^2} + 9x = 5\sin 3t$, $x(0) = 2$, $x'(0) = 0$

39. **(a)** Show that the solution of the initial-value problem

$$\frac{d^2x}{dt^2} + \omega^2 x = F_0 \cos \gamma t, \quad x(0) = 0, \quad x'(0) = 0$$

is

$$x(t) = \frac{F_0}{\omega^2 - \gamma^2}(\cos \gamma t - \cos \omega t).$$

(b) Evaluate $\displaystyle\lim_{\gamma \to \omega} \frac{F_0}{\omega^2 - \gamma^2}(\cos \gamma t - \cos \omega t)$.

40. Compare the result obtained in part (b) of Problem 39 with the solution obtained using variation of parameters when the external force is $F_0 \cos \omega t$.

41. **(a)** Show that $x(t)$ given in part (a) of Problem 39 can be written in the form

$$x(t) = \frac{-2F_0}{\omega^2 - \gamma^2} \sin \frac{1}{2}(\gamma - \omega)t \sin \frac{1}{2}(\gamma + \omega)t.$$

(b) If we define $\varepsilon = \frac{1}{2}(\gamma - \omega)$, show that when ε is small an approximate solution is

$$x(t) = \frac{F_0}{2\varepsilon\gamma} \sin \varepsilon t \sin \gamma t.$$