MAE Preliminary Examination
Mathematics Section

Monday, November 14, 9:00am-12noon

Your Name

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<td>Select the 3 problems you’ve worked, to be graded:</td>
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Please give your answers/work in the space provided
Explain your work/steps clearly
Linear Algebra: Problem 1 [10 points]:

i) Consider the $2 \times 2$ matrix

$$P = \begin{bmatrix} 2 & 3 \\ 3 & 5 \end{bmatrix}.$$ 

Determine a matrix $S$ such that $P = SS'$. 

ii) Explain in general, for a symmetric matrix $P$ when it is possible to obtain such a factorization $P = SS'$ and how this can be accomplished.

iii) Suppose that a matrix $A$ and its transpose $A'$ satisfy an equation of the form

$$PA = A'P$$

for a positive definite matrix $P$. Show that $A$ has real simple eigenvalues. (Hint: Consider searching for a similarity transformation that makes $B = SAS^{-1}$ symmetric.)

Workspace for Problem 1: Explain your reasoning/work here.

**Solution:**

i) Although this can be accomplished in a brute force way, by searching of such an algebraic factorization directly since this is only $2 \times 2$, a systematic way is to compute the square root of the matrix just as we would do for any other function of the matrix (by spectral decomposition). Specifically we first compute the eigendecomposition

$$P = \begin{bmatrix} -1.618 & 1 \\ 1 & 1.618 \end{bmatrix} \begin{bmatrix} \frac{7-\sqrt{45}}{2} & 0 \\ 0 & \frac{7+\sqrt{45}}{2} \end{bmatrix} \begin{bmatrix} -1.618 & 1 \\ 1 & 1.618 \end{bmatrix}^{-1}$$

and then construct the square root of $P$ setting

$$S = \begin{bmatrix} -1.618 & 1 \\ 1 & 1.618 \end{bmatrix} \begin{bmatrix} \sqrt{\frac{7-\sqrt{45}}{2}} & 0 \\ 0 & \sqrt{\frac{7+\sqrt{45}}{2}} \end{bmatrix} \begin{bmatrix} -1.618 & 1 \\ 1 & 1.618 \end{bmatrix}^{-1} = \begin{bmatrix} 1 & 1 \\ 1 & 2 \end{bmatrix}.$$ 

ii) The construction in i) is general. I.e., we start with an eigendecomposition

$$P = VDV^{-1}$$

where $D$ is diagonal and, as long as $P > 0$, we can take the square roots of the diagonal elements (eigenvalues) in $D$ to construct

$$S = V\sqrt{D}V^{-1}.$$ 

iii) It is well known and easy to show that any symmetric matrix has real eigenvalues. (To see this, simply consider $v^*Av = \lambda v^*v$ with $v$ the eigenvector corresponding to the eigenvalue $\lambda$. Taking complex conjugates of both sides, $\lambda = \bar{\lambda}$ and hence, real.)

So we only need to show that $A$ can be transformed to a symmetric matrix via a similarity transformation. For then, $B = SAS^{-1} = B'$ will have real eigenvalues, which would be identical to those of $A$.

To see this last statement in the hint, simply consider the factorization $P = SS$ as before, since $P > 0$. (We could also use $P = SS'$, with the extra complication of carrying primes in the needed computations.) Then

$$SSA = A'SS \Rightarrow B = SAS^{-1} = S^{-1}A'S = B'$$

which is exactly what we wanted to prove.
Differential Equations: Problem 2 [10 points]:

Consider the physical system shown above that consists of a hoop (big thick circle) that rotates about the \( z \) axis with angular velocity \( \omega \). The angular position of its plane with respect to the \( x \) axis is indicated by \( \omega t \), where \( t \) denotes time. A ring/bead (small circle denoted “ring”) is placed on the hoop which can freely move up and down with a small amount of friction. The angular location of this ring/bead with respect to the center of the hoop is denoted by \( \theta \).

The equation of motion that dictates the position \( \theta \) of the ring, as the hoop rotates, is given by

\[
\ddot{\theta} + \mu \dot{\theta} + \left( \frac{g}{R} \right) \sin(\theta) - \omega^2 \sin(\theta) \cos(\theta) = 0,
\]

where \( \mu \) can be considered constant. Do the following:

i) Write down the dynamical equation in state-space form. [Hint: set \( x_1(t) = \theta(t) \), \( x_2(t) = \dot{\theta}(t) \), and treat \( \mu, g, R, \omega \) as constants.]

ii) Determine the angular positions for the ring/bead that correspond to points of equilibrium. i.e., determine values of \( \theta \) where the bead can be found at steady-state for a fixed angular velocity \( \omega \) of the hoop. These points may depend on the value of the angular velocity \( \omega \). Clearly, one of them is \( \theta = 0 \) but there may be one more.

iii) Classify these possible points of equilibrium (i.e., stable, unstable, node, focus, etc.).

[Hint: the stability of these points of equilibrium may depend on the value of \( \omega \) for fixed values of \( g, R \). For instance, \( \theta_0 = 0 \) is one angle that corresponds to an equilibrium, but this may not be stable depending on the value of \( \omega \).]

Above, \( R > 0 \) is the radius of the hoop, \( \mu > 0 \) is a coefficient of friction, and \( g = 9.81 \text{[m/sec}^2] \) denotes the acceleration due to gravity, and note that the dynamics of the ring are second order (since \( \omega \) is thought of being constant) and the dynamical equation involves only the second derivative of \( \theta \).
Solution:

i) For $x_1 = \theta, \ x_2 = \dot{\theta}$, the dynamical equation is

$$\frac{d}{dt} \begin{pmatrix} x_1 \\ x_2 \end{pmatrix} = \begin{pmatrix} \frac{g}{R} \sin(x_1) + \omega^2 \sin(x_1) \cos(x_1) - \mu x_2 \\ x_2 - g/R \sin(x_1) + \omega^2 \sin(x_1) \cos(x_1) - \mu x_2 \end{pmatrix} = f(x_1, x_2).$$

ii) To determine points of equilibrium, we need $\dot{\theta} = \ddot{\theta} = 0$, i.e., $\dot{x}_1 = \dot{x}_2 = 0$,

$$(g/R) \sin(\theta) - \omega^2 \sin(\theta) \cos(\theta) = 0.$$

Hence, there are points of equilibrium at $\theta_0 = 0$ and $\theta_1 = \pi$, and, possibly, an additional point of equilibrium at $\theta_2 = \arccos(\frac{g}{R\omega^2})$, but only when $g < R\omega^2$.

iii) For $\theta_0 = 0$, i.e., $(x_1, x_2) = (0, 0)$ and the linearized dynamics $\dot{x} = Ax$ correspond to:

$$A = \frac{\partial f}{\partial x} = \begin{pmatrix} 0 & 1 \\ -\frac{g}{R} + \omega^2 & -\mu \end{pmatrix}$$

Thus, if $\omega = 0$, and if $\mu^2 > 4g/R$, then the equilibrium at $\theta_0$ is a stable node, if $\mu^2 < 4g/R$, then it is a stable focus (damped oscillations).

The characteristic exponent

$$-\mu + \sqrt{\mu^2 - 4(g/R) + 4\omega^2}$$

is negative when $R\omega^2 < g$, i.e.,

$$\omega < \sqrt{g/R}.$$ 

If this holds, the equilibrium is stable, otherwise it is unstable (and marginally so, if $\omega = \sqrt{g/R}$).

The equilibrium is a stable focus as long as, in addition to stability, $\mu < 2\sqrt{g/R - \omega^2}$, otherwise it is a stable node.

As we increase $\omega$ further, the characteristic exponent becomes zero when $\omega = \sqrt{g/R}$, and for $\omega > \sqrt{g/R}$, the equilibrium at $\theta_0 = 0$ is an unstable focus. For such values of $\omega$, $\theta_2$ becomes an attractive equilibrium (below).

iii_1) At $\theta_1 = \pi$, the equilibrium is clearly unstable. The state matrix at the corresponding equilibrium is

$$A = \frac{\partial f}{\partial x} = \begin{pmatrix} 0 & 1 \\ \frac{g}{R} + \omega^2 & -\mu \end{pmatrix}$$

iii_2) For $\theta_2 = \arccos(\frac{g}{R\omega^2})$, i.e., $(x_1, x_2) = (\arccos(\frac{g}{R\omega^2}), 0)$ the linearized dynamics correspond to

$$A = \frac{\partial f}{\partial x} = \begin{pmatrix} 0 & 1 \\ \frac{g^2}{R^2\omega^2} - \omega^2 & -\mu \end{pmatrix}$$

The equilibrium (exists and it) is stable for $\omega > \sqrt{g/R}$ and $\mu > 0$.

The equilibrium is a node for $\mu^2 + 4(\frac{g^2}{R^2\omega^2} - \omega^2) > 0$, and a focus otherwise.