	SEAT	Ma				No. of	Printed Page	es :2
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	[72	J		ΛΙΝΑΤΙΟΝ(Se				
	- r	_	D.SC. EAM	, 24th Decemi	har	2020		
				p.m. to 4:00		1.		
				ubject: PHYSI		_		
				rse: US05CPF				
			Title:	Classical Med	har	nics		
							Total Ma	rks:/U
v.B:	(i) All th	ie syn	nbol have their usua	l meanings				
	(ii) Figur	es at	the right side of qu	estions indicate	full i	marks	•	(4.0)
Q-1	Multip	le Ch	oice Questions (Att	empt All)				(10)
•	(1)	The d	egree of freedom fo	or N particles in				
		(a)	N		(b)			
		(c)	3N		(d)	2		
	(2)			are independe	nt o	t time	an lo	
			Holonomic			Non-Holonor		
		(c)	Scleronomous			Rheonomous		
	(3)	The g	generalized coordin	ates for spherica	ai pe	noulum are _		
		(a)	a & θ			θ&φ 0&φ		
		(c)	α&φ moving frame of r	afavanca is acce	(u) dora	υν φ Stad the effect	rive force actir	ıģ ·
	(4)	If the	moving trame of r	than the acce	rtual	force		Ü
			ne particle is	than the at	/h)	equal		4
		(a)	zero smaller		(d)		the second of the	
	/51	(c)	id body have	degree of	• ,	-		
	(5)	(a)	one		(b)	two		
		101	three		(d)	six	•	
	(6)	The	path of a particle	isw	hen	it is moving	under consta	int
	(0)	cons	servative force field	-				
	÷	(a)	cycloid		(b)	hyperbolic		
		- (c)	parabolic		(d)	_		
	(7)	The	equation of constra	ints for a simpl	e pe	ndulum is		
	` .	(a)	$r d\theta - l = 0$		(b)	r-l=0	•	
		(c)	r+l=0		(d)	$r d\theta + l =$	0	
	(8)	For	conservative syster	n, the potential	ene	rgy is a tunctio	in of	-
		(a)	position		(b) velocity		
		(c)	force		(d) acceleration		
	(9)	The	space depends on	position coordi	nate	and momenta	1 is caned	
		spa	ce		11	l phoso		
		(a)		ş.,) phase :	n ·	
			coordinate		(a) momentun	H	
	(10)		Poisson brackets a	re	/1-) non-distrib	nutive	
		(a)			(b (c	*	nutative	•
		- (c)	commutative		Ιc	ү анцгоония		

Q-2	2 True-False and Filling the blanks					
	(1) When the constraints are depends on the time are known as	(08)			
		Miconomous constraints (True/False)				
	(2	The study of conservation theorems for a system in motion provides the				
		constants of motion (True/False)				
	(3)) In a torque free motion of a rigid body, the angular velocity, of the body				
		is a constant vector (True/False)				
	(4)	* * * * * * * * * * * * * * * * * * *				
	(5)	In variational principle the line integral of some function between two end points is				
	(6)					
	(7)	o o re a gracues confection 12 F =				
	(8)	In Hamiltonian formulation notion condition				
	1-7	In Hamiltonian formulation potion coordinate and taken as independent variable				
Q-3	Short Questions (Attempt any Ten)					
	(1)	What are generalised coordinates?	(20)			
	(2)	Write the advantages of Lagrangian formulation				
	(3)	Write the Maxwell's equations				
	(4)	Find the angular velocity of the earth				
,	(5)	Show that the directions of the angular velocity and the angular momentum are different				
	(6)	Define inertial and non-inertial frame of reference				
	(7)	State the Hamilton's principle				
	(8)	What is necessity of undetermined multipliers?				
	(9)	What is configuration space?				
	(10)	Construct the Lagrangian for simple pendulum with moving support				
	(11)	what is a phase diagram?				
	(12)	What is Generating function?				
Q-4	Long	Questions (Attempt any four) All questions carry equal marks	32)			
	(1)	Derive the Lagrange's equation of the derivative of the lagrange's equation of the lagrange's equatio	321			
	(2)	Derive the Lagrange's equation of motion for a Rayleigh's dissipation				
		iunction				
	(3)	Explain the motion of the earth with necessary diagrams				
	(4)	Derive the expressions of angular momentum and kinetic energy for				
		motion of rigid body				
-	(5)	Discuss the technique of calculus of variation and derive the Euler's				
		equation $\frac{\partial f}{\partial y} - \frac{\partial f}{\partial x} \left(\frac{\partial f}{\partial y'} \right) = 0$				
	(6)	Construct the Lagrangian and derive the equations of motion for a				
		cylinder rolling on inclined plane using undetermined multiplier				
	(7)	Deduce the Hamilton's equation of motion and show that His a constant				
		of motion and also give the total energy				
	(8)	Discuss the Canonical transformation and derive the Canonical				
		transformation equation for $F_1 = F_1(q_i, Q_i, t)$				