Exploring Physics with C++

Zvonimir Vanjak

EXPLORING PHYSICS WITH C++

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Preface

Motivacija

- Iako ima knjiga koje koriste C++ kao programski jezik za prezentaciju tehnika numerical computinga, taj C++ je zastarjelog (C-like) stila I ne koristi ni blizu sve mogućnosti modernog C++a
- Što se tiče korištenja softvera za istraživanje fizike, postoji priličpno opsežna lioteratura u kojoj se koriste Matlab I Mathematica, u zadnjih par godina ima I sve više knjiga koje koriste Python u takvu svrhu, ali nema baš takve knjige za C++

Osobno

- Tema me fascinira 30 godina, otkad sam prvi put u ruke uzeo Numerical Recipes in C
- A fascinira me I fizika ❤️‍🩹
- I izvrsna je prilika za re-learning, I fizike I ažuriranje znanja C++a

Osnovni cilj je istražiti različite fizikalne pojave, zakonitosti I generalno različite situacije, koristeći C++ za provođenje numeričkih proračuna

Te uz to opisati I relevantnu fiziku I osnovne tehnike numerical computinga koje će se koristiti

Nekakav početni okvir za raspored po količini sadržaja bi bio: 30% fizike, 40% numerical computing, 30% konkretan C++ kôd

Pregled poglavlja

1. Prva tri – osnovni objekti, algoritmi I vizualizacija
2. Osnovna mehanika – 4, 5, 6, I 7
3. Gravity – 8 I 9
4. Inertial, non-inertial frames and coordinate transformations – 10, 11 I 12
5. Rigid body – 13 I 14
6. Special relativity – 15 I 16
7. Electromagnetism – 17, 18, 19
8. Curves and surfaces – 20
9. General relativity - 21

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1. Essential mathematical objects

Where we start from the beginning.

PRELIMINARIES

Doing numerics on computer – challenges, pitfalls and traps

Representing numbers

Precision of real representation

about IEEE754, mantissa, exponents, and all that

TODO – table with precision and ranges for single and double precision

Roundoff errors

Couple of examples of roundoff errors

Special emphasis on subtraction of similar numbers

Truncation errors

Numerical computing in modern C++

TODO – minimal history, advances, still going extra strong, future plans for C++26

Has come a long way since times when even PI was not part of the standard.

Still, there is no POW2 in C++!

But there are great numerical libraries

GSL – GNU Scientific Library

Link and short overview.

Boost.Math

Link, overview.

Especially Boost.Math toolkit.

Starting our own Minimal Math Library

Why not just use Boost or GSL?

- Learning by implementing
- Creating general math library that is versatile and easily usable
- And that also has basic mathematical objects directly modelled (in today's parlance, you could say it is "opinionated")

C++20 is our starting point

MMLBase.h

This will be the base header for our library.

Starting with necessary headers we need to include

```
#include <stdexcept>
#include <initializer_list>
#include <algorithm>
#include <memory>
#include <functional>

#include <string>
#include <vector>
#include <fstream>
#include <iostream>
#include <iomanip>

#include <cmath>
#include <limits>
#include <complex>
#include <numbers>
```

Following good programming practice, all our code will be within namespace MML

Some basics

```
namespace MML
{
  template<class Type>
  static Real Abs(const Type& a)
  {
    return std::abs(a);
  }
  template<class Type>
  static Real Abs(const std::complex<Type>& a)
  {
    return hypot(a.real(), a.imag());
  }
  inline bool isWithinAbsPrec(Real a, Real b, Real eps)
  {
    return std::abs(a - b) < eps;
  }
  inline bool isWithinRelPrec(Real a, Real b, Real eps)
  {
    return std::abs(a - b) < eps * std::max(Abs(a), Abs(b));
  }

  template<class T> inline T POW2(const T a) { const T t=a; return t * t; }
  template<class T> inline T POW3(const T a) { const T t=a; return t * t * t; }
  template<class T> inline T POW4(const T a) { const T t=a; return t * t * t * t; }
```

Constants

TODO – do some thinking about this (and possibly expand list!)

```
////////////                  Constants                ////////////////
namespace Constants
{
  static inline const Real PI = std::numbers::pi;
  static inline const Real Epsilon = std::numeric_limits<Real>::epsilon();
  static inline const Real PositiveInf = std::numeric_limits<Real>::max();
  static inline const Real NegativeInf = -std::numeric_limits<Real>::max();
}
```

Some defaults for precision of numerical operations

```
namespace Defaults
{
  static int VectorPrintWidth = 15;
  static int VectorPrintPrecision = 10;

  //////////              Default precisions             ///////////
  // TODO - how to make dependent on Real type
  // //     (ie. different values for float, double and long double)
  static inline const double ComplexEqualityPrecision = 1e-15;
  static inline const double ComplexAbsEqualityPrecision = 1e-15;
  static inline const double MatrixEqualityPrecision = 1e-15;
  static inline const double VectorEqualityPrecision = 1e-15;

  static inline const double IsMatrixSymmetricPrecision = 1e-15;
  static inline const double IsMatrixDiagonalPrecision = 1e-15;
  static inline const double IsMatrixUnitPrecision = 1e-15;
  static inline const double IsMatrixOrthogonalPrecision = 1e-15;
```

And list of all available standard and special functions in C++20 standard

```
static inline Real Sin(Real x) { return sin(x); }
static inline Real Cos(Real x) { return cos(x); }
static inline Real Sec(Real x) { return 1.0 / cos(x); }
static inline Real Csc(Real x) { return 1.0 / sin(x); }
static inline Real Tan(Real x) { return tan(x); }
static inline Real Ctg(Real x) { return 1.0 / tan(x); }

static inline Real Exp(Real x) { return exp(x); }
static inline Real Log(Real x) { return log(x); }
static inline Real Log10(Real x){ return log10(x); }
static inline Real Sqrt(Real x) { return sqrt(x); }
static inline Real Pow(Real x, Real y) { return pow(x, y); }

static inline Real Sinh(Real x) { return sinh(x); }
static inline Real Cosh(Real x) { return cosh(x); }
static inline Real Sech(Real x) { return 1.0 / cosh(x); }
static inline Real Csch(Real x) { return 1.0 / sinh(x); }
static inline Real Tanh(Real x) { return tanh(x); }
static inline Real Ctgh(Real x) { return 1.0 / tanh(x); }

static inline Real Asin(Real x) { return asin(x); }
static inline Real Acos(Real x) { return acos(x); }
static inline Real Atan(Real x) { return atan(x); }

static inline Real Asinh(Real x) { return asinh(x); }
static inline Real Acosh(Real x) { return acosh(x); }
static inline Real Atanh(Real x) { return atanh(x); }
```

Special functions

```
static inline Real Erf(Real x)  { return std::erf(x); }
static inline Real Erfc(Real x) { return std::erfc(x); }

static inline Real TGamma(Real x) { return std::tgamma(x); }
static inline Real LGamma(Real x) { return std::lgamma(x); }
static inline Real RiemannZeta(Real x) { return std::riemann_zeta(x); }
static inline Real Comp_ellint_1(Real x) { return std::comp_ellint_1(x); }
static inline Real Comp_ellint_2(Real x) { return std::comp_ellint_2(x); }

static inline Real Hermite(unsigned int n, Real x) { return std::hermite(n, x); }
static inline Real Legendre(unsigned int n, Real x) { return std::legendre(n, x); }
static inline Real Laguerre(unsigned int n, Real x) { return std::laguerre(n, x); }
static inline Real SphBessel(unsigned int n, Real x) { return std::sph_bessel(n, x); }
static inline Real SphLegendre(int n1, int n2, Real x) { return std::sph_legendre(n1, n2, x); }
```

MMLExceptions.h

Even though having exceptions in our code exacts (quite) small runtime penalty, it is a small price for having dependable way of handling exceptional situations .

Set of interface classes defined in MMLExceptions.h

Running code and examples

All code available on Github (https://github.com/zvanjak/ExploringPhysicsWithCpp)

Using Visual studio code with standard extensions for C++ development

Working with different compilers – tested on MSVC, Clang, gcc

Tested on different platforms – Windows, Linux, Mac.

VECTOR – "THE WORKHORSE"

What is a vector?

Can represent almost anything, and in our physics investigations we'll use it to represent Cartesian and spherical vectors, momentum and angular momentum, …

but in essence, it is an array of numbers, real or complex, of some determined size and it is present in almost all numerical calculations.

Templated – so it can contain any kind of type

Two types.

- Runtime size
- Compile time size

Vector<Type> - runtime size

Represents (mathematical!) vector of dynamically defined size, and it is basically a wrapper around std::vector<>.

Delegation, not inheritance! As we will be at the same time restricting set of operations available from std::vector<> and extending that set with some mathematical operations, not present in std::vector<>.

```
template<class Type>
class Vector
{
private:
  std::vector<Type> _elems;

public:
  typedef Type value_type;      // make T available externally

  ////////////////////                Constructors                ////////////////////
  Vector() {}
  explicit Vector(int n) { ... }
  explicit Vector(int n, const Type &val) { ... }
  explicit Vector(int n, Type* vals) { ... }
  explicit Vector(std::vector<Type> values) : _elems(values) {}
  explicit Vector(std::initializer_list<Type> list) : _elems(list) {}
```

For accessing element, we implement two approaches – with and without bounds checking.

```
//////////////////////          Accessing elements            //////////////////////
inline Type&       operator[](int n)       { return _elems[n]; }
inline const Type& operator[](int n) const { return _elems[n]; }

// checked access
Type& at(int n) {
  if(n < 0 || n >= size())
    throw VectorDimensionError("Vector::at - index out of bounds", size(), n);
  else
    return _elems[n];
}
Type  at(int n) const {
  if(n < 0 || n >= size())
    throw VectorDimensionError("Vector::at - index out of bounds", size(), n);
  else
    return _elems[n];
}
```

Set of implemented arithmetic operators.

```
//////////////////////          Arithmetic operators          //////////////////////
Vector  operator-() const { ... }

Vector  operator+(const Vector& b) const { ... }
Vector& operator+=(const Vector& b) { ... }
Vector  operator-(const Vector& b) const { ... }
Vector& operator-=(const Vector& b) { ... }

Vector  operator*(Type b) { ... }
Vector& operator*=(Type b) { ... }
Vector  operator/(Type b) { ... }
Vector& operator/=(Type b) { ... }

friend Vector operator*(Type a, const Vector& b) { ... }
```

Operations for testing equality

```
//////////////////////            Testing equality            //////////////////////
bool operator==(const Vector& b) const { ... }
bool operator!=(const Vector& b) const { ... }
bool IsEqualTo(const Vector& b, Real eps = Defaults::VectorEqualityPrecision) const { ... }
bool IsNullVec() const { ... }
```

Calculating vector norm

```
//////////////////////                Operations
Real NormL1() const { ... }
Real NormL2() const { ... }
Real NormLInf() const { ... }
```

I/O for vectors

```
//////////////////////////             I/O              //////////////////////////
std::ostream& Print(std::ostream& stream, int width, int precision) const { ... }
std::ostream& Print(std::ostream& stream, int width, int precision, Real zeroThreshold) const { ... }
std::ostream& PrintLine(std::ostream& stream, const std::string &msg, int width, int precision) const { ... }

std::string to_string(int width, int precision) const { ... }
friend std::ostream& operator<<(std::ostream &stream, const Vector &a) { ... }
```

VectorN<Type, N> - compile-time size

Vector with statically defined size.

Needed mostly in its 2D, 3D or 4D incarnations, where it will be used as base class for some specific implementations.

Has mostly the same functionality as Vector, with obvious difference in data declaration and minor differences in constructors.

```
template<class Type, int N>  <T> Provide sample template arguments for IntelliSense
class VectorN
{
protected:
  Type  _val[N] = { 0 };

public:
  typedef Type value_type;      // make T available externally

  ////////////////////          Constructors and destructor       ////////////////////
  VectorN() {}
  explicit VectorN(const Type& init_val) { ... }
  explicit VectorN(std::initializer_list<Type> list) { ... }
  explicit VectorN(std::vector<Type> list) { ... }
  explicit VectorN(Type* vals) { ... }
```

Starting our BaseUtils class

Utility class with static helpers of various kinds and stuff that even though it is closely associated with Vector class, doesn't merit inclusion as pure member.

In some cases, it is actually impossible to preserve semantics, as in case of ScalarProduct() helper function where implementation for Real and Complex types is different.

Here are the vector helpers

```
//////////////////                  Vector helpers                  //////////////////
static bool AreEqual(const Vector<Real> &a, const Vector<Real> &b, Real eps = Defaults::VectorEqualityPrecision) { ... }
static bool AreEqual(const Vector<Complex>& a, const Vector<Complex>& b, double eps = Defaults::ComplexEqualityPrecision) { ...
static bool AreEqualAbs(const Vector<Complex>& a, const Vector<Complex>& b, double eps = Defaults::ComplexAbsEqualityPrecision)

static Real    ScalarProduct(const Vector<Real>& a, const Vector<Real>& b) { ... }
static Complex ScalarProduct(const Vector<Complex>& a, const Vector<Complex>& b) { ... }

template<int N>
static Real    ScalarProduct(const VectorN<Real, N> &a, const VectorN<Real, N> &b) { ... }
template<int N>
static Complex ScalarProduct(const VectorN<Complex, N>& a, const VectorN<Complex, N>& b) { ... }

static Vector<Real> VectorProjectionParallelTo(const Vector<Real>& orig, const Vector<Real>& b) { ... }
static Vector<Real> VectorProjectionPerpendicularTo(const Vector<Real>& orig, const Vector<Real>& b) { ... }

static Real VectorsAngle(const Vector<Real> &a, const Vector<Real> &b) { ... }
template<int N>
static Real VectorsAngle(const VectorN<Real, N> &a, const VectorN<Real, N> &b) { ... }
```

Unfortunately, mixing operations between different Vector types requires special functions.

```
//////////////////       Vector<Complex> - Vector<Real> operations       //////////////////
static Vector<Complex> AddVec(const Vector<Complex>& a, const Vector<Real>& b) { ... }
static Vector<Complex> AddVec(const Vector<Real>& a, const Vector<Complex>& b) { ... }

static Vector<Complex> SubVec(const Vector<Complex>& a, const Vector<Real>& b) { ... }
static Vector<Complex> SubVec(const Vector<Real>& a, const Vector<Complex>& b) { ... }
```

Example usage

TODO – example with vectors and its operations.

MATRIX – "THE OMNIPRESENT"

Used everywhere …

Matrix<Type> - runtime size

Standard Matrix object with size defined at runtime, ie. at construction time.

Space for storing elements is allocated as contiguous block (not on a per row basis).

Set of available constructors.

```
template<class Type>
class Matrix
{
private:
  int  _rows;
  int  _cols;
  Type** _data;

  void Init(int rows, int cols) { ... }

public:
  typedef Type value_type;      // make Type available externally

  ////////////////////          Constructors and destructor       ////////////////////
  explicit Matrix() : _rows(0), _cols(0), _data{ nullptr } {}
  explicit Matrix(int rows, int cols) { ... }
  explicit Matrix(int rows, int cols, const Type& val) { ... }
  // useful if you have a pointer to continuous 2D array (can be in row-, or column-wise memory layout)
  explicit Matrix(int rows, int cols, Type* val, bool isRowWise = true) { ... }
  // in strict mode, you must supply ALL necessary values for complete matrix initialization
  explicit Matrix(int rows, int cols, std::initializer_list<Type> values, bool strictMode = true) { ... }

  Matrix(const Matrix& m) { ... }
  // creating submatrix from given matrix 'm'
  Matrix(const Matrix& m, int ind_row, int ind_col, int row_num, int col_num) { ... }
  Matrix(Matrix&& m) { ... }
  ~Matrix() { ... }

  void Resize(int rows, int cols) { ... }
```

Basics stuff, and some manipulation routines.

```
//////////////////////              Standard stuff               //////////////////////
inline int RowNum() const { return _rows; }
inline int ColNum() const { return _cols; }

static Matrix GetUnitMatrix(int dim) { ... }
void   MakeUnitMatrix(void) { ... }

Matrix GetLower(bool includeDiagonal = true) const { ... }
Matrix GetUpper(bool includeDiagonal = true) const { ... }

void SwapRows(int k, int l) { ... }
void SwapCols(int k, int l) { ... }

//////////////////////         Matrix to Vector conversions      //////////////////////
Vector<Type> VectorFromRow(int rowInd) const { ... }
Vector<Type> VectorFromColumn(int colInd) const { ... }
Vector<Type> VectorFromDiagonal() const { ... }
```

Functions for calculating various matrix properties.

```
//////////////////////              Matrix properties            //////////////////////
bool IsUnit(double eps = Defaults::IsMatrixUnitPrecision) const { ... }
bool IsDiagonal(double eps = Defaults::IsMatrixDiagonalPrecision) const { ... }
bool IsDiagDominant() const { ... }
bool IsSymmetric() const { ... }
bool IsAntiSymmetric() const { ... }

Real NormL1() const { ... }
Real NormL2() const { ... }
Real NormLInf() const { ... }
```

Assignment and access operators.

```
//////////////////////            Assignment operators           //////////////////////
Matrix& operator=(const Matrix& m) { ... }
Matrix& operator=(Matrix&& m) { ... }

//////////////////////              Access operators             //////////////////////
inline Type*        operator[](int i)             { return _data[i]; }
inline const Type*  operator[](const int i) const { return _data[i]; }

inline Type  operator()(int i, int j) const { return _data[i][j]; }
inline Type& operator()(int i, int j)       { return _data[i][j]; }

// version with checked access
Type  at(int i, int j) const { ... }
Type& at(int i, int j) { ... }
```

Two ways to check for equality – exact, implemented with operators == and !=, and within given precision

```
//////////////////////              Equality operations          //////////////////////
bool operator==(const Matrix& b) const { ... }
bool operator!=(const Matrix& b) const { ... }

bool IsEqualTo(const Matrix<Type>& b, Type eps = Defaults::MatrixEqualityPrecision) const { ... }
static bool AreEqual(const Matrix& a, const Matrix& b, Type eps = Defaults::MatrixEqualityPrecision)
```

Standard set of arithmetic operators.

```
//////////////////////              Arithmetic operators          //////////////////////
Matrix  operator-() const { ... }

Matrix  operator+(const Matrix& b) const { ... }
Matrix& operator+=(const Matrix& b) { ... }
Matrix  operator-(const Matrix& b) const { ... }
Matrix& operator-=(const Matrix& b) { ... }
Matrix  operator*(const Matrix& b) const { ... }

Matrix  operator*(const Type &b) const { ... }
Matrix& operator*=(const Type &b) { ... }
Matrix  operator/(const Type &b) const { ... }
Matrix& operator/=(const Type& b) { ... }

Vector<Type> operator*(const Vector<Type>& b) const { ... }

friend Matrix operator*(const Type &a, const Matrix<Type>& b) { ... }
friend Vector<Type> operator*(const Vector<Type>& a, const Matrix<Type>& b) { ... }
```

Basic operations, where matrix inversion is performed by using Gauss-Jordan elimination with pivoting.

```
//////////////////////           Trace, Inverse & Transpose      //////////////////////
Type   Trace() const { ... }

void   Invert() { ... }
Matrix GetInverse() const { ... }

void   Transpose() { ... }
Matrix GetTranspose() const { ... }
```

Printing to console and working with files

```
//////////////////////                  I/O                  //////////////////////
void   Print(std::ostream& stream, int width, int precision) const { ... }
void   Print(std::ostream& stream, int width, int precision, Real zeroThreshold) const { ... }

friend std::ostream& operator<<(std::ostream& stream, const Matrix& a) { ... }
std::string to_string(int width, int precision) const { ... }

static bool LoadFromFile(std::string inFileName, Matrix& outMat) { ... }
static bool SaveToFile(const Matrix& mat, std::string inFileName) { ... }
```

MatrixNM<Type, N, M> - compile-time size

Different from Matrix in additional template parameters, and internal structure, but basically the same in functionality.

```
template <class Type, int N, int M>
class MatrixNM
{
public:
  Type _vals[N][M] = { {0} };

public:
  typedef Type value_type;      // make T available externally

  //////////////////////////            Constructors           //////////////////////////
  MatrixNM() {}
  MatrixNM(std::initializer_list<Type> values) { ... }
  MatrixNM(const MatrixNM& m) { ... }
  MatrixNM(const Type& m) { ... }
```

Extending BaseUtils with matrix helpers

Similarly to Vector helpers, we add to our BaseUtils.h header various helper for Matrix classes.

```
//////////////////            Creating Matrix from Vector             //////////////////
template<class Type> static Matrix<Type> RowMatrixFromVector(const Vector<Type>& b) { ... }
template<class Type> static Matrix<Type> ColumnMatrixFromVector(const Vector<Type>& b) { ... }
template<class Type> static Matrix<Type> DiagonalMatrixFromVector(const Vector<Type>& b) { ... }

template<class Type, int N> MatrixNM<Type, 1, N> RowMatrixFromVector(const VectorN<Type, N>& b) { ..
template<class Type, int N> MatrixNM<Type, N, 1> ColumnMatrixFromVector(const VectorN<Type, N>& b) {
template<class Type, int N> MatrixNM<Type, N, N> DiagonalMatrixFromVector(const VectorN<Type, N>& b)


//////////////////                Matrix helpers                //////////////////
template<class Type> static Matrix<Type> Commutator(const Matrix<Type>& a, const Matrix<Type>& b) { .
template<class Type> static Matrix<Type> AntiCommutator(const Matrix<Type>& a, const Matrix<Type>& b)

template<class Type>
static void MatrixDecomposeToSymAntisym(const Matrix<Type>& orig,
                                        Matrix<Type>& outSym,
                                        Matrix<Type>& outAntiSym) { ... }

//////////////////              Matrix functions                //////////////////
template<class Type> static Matrix<Type> Exp(const Matrix<Type>& a, int n = 10) { ... }
template<class Type> static Matrix<Type> Sin(const Matrix<Type>& a, int n = 10) { ... }
template<class Type> static Matrix<Type> Cos(const Matrix<Type>& a, int n = 10) { ... }
```

Calculating different matrix properties

```
//////////////////                Real matrix helpers                  //////////////////
static bool IsOrthogonal(const Matrix<Real>& mat, double eps = Defaults::IsMatrixOrthogonalPrecision)

//////////////////              Complex matrix helpers                 //////////////////
static Matrix<Real> GetRealPart(const Matrix<Complex>& a) { ... }
static Matrix<Real> GetImagPart(const Matrix<Complex>& a) { ... }

static Matrix<Complex> GetConjugateTranspose(const Matrix<Complex>& mat) { ... }
static Matrix<Complex> CmplxMatFromRealMat(const Matrix<Real>& mat) { ... }

static bool IsComplexMatReal(const Matrix<Complex>& mat) { ... }
static bool IsHermitian(const Matrix<Complex>& mat) { ... }
static bool IsUnitary(const Matrix<Complex>& mat) { ... }
```

Set of functions for performing arithmetic between Real and Complex matrices

```
//////////////////       Matrix<Complex> - Matrix<Real>  operations     //////////////////
static Matrix<Complex> AddMat(const Matrix<Complex>& a, const Matrix<Real>& b) { ... }
static Matrix<Complex> AddMat(const Matrix<Real>& a, const Matrix<Complex>& b) { ... }

static Matrix<Complex> SubMat(const Matrix<Complex>& a, const Matrix<Real>& b) { ... }
static Matrix<Complex> SubMat(const Matrix<Real>& a, const Matrix<Complex>& b) { ... }

static Matrix<Complex> MulMat(const Complex& a, const Matrix<Real>& b) { ... }
static Matrix<Complex> MulMat(const Matrix<Real>& a, const Complex& b) { ... }

static Matrix<Complex> MulMat(const Matrix<Complex>& a, const Matrix<Real>& b) { ... }
static Matrix<Complex> MulMat(const Matrix<Real>& a, const Matrix<Complex>& b) { ... }

static Vector<Complex> MulMatVec(const Matrix<Real>& a, const Vector<Complex>& b) { ... }
static Vector<Complex> MulMatVec(const Matrix<Complex>& a, const Vector<Real>& b) { ... }

static Vector<Complex> MulVecMat(const Vector<Complex>& a, const Matrix<Real>& b) { ... }
static Vector<Complex> MulVecMat(const Vector<Real>& a, const Matrix<Complex>& b) { ... }
```

Example usage

TODO – example with matrices

FUNCTIONS AS FULL-FLEDGED OBJECTS

Function pointers have been in C and C++ from the start.

C++ introduced other options:

- Functors, ie. objects that overload operator()
- Using templates (with use of operator() overloading)
- lambdas

The most general approach is the one taken in Numerical Recipes in C++, where each "function" parameter is actually a template parameter, expecting only implementation of operator().

In an "opinionated" manner of our implementation, we will define a set of interfaces and treat functions as full-fledged objects

All interfaces are specified in IFunction.h header

General function definition:

```
template<typename _RetType, typename _ArgType>
class IFunction
{
public:
  virtual _RetType operator()(_ArgType) const = 0;

  virtual ~IFunction() {}
};
```

Breaking YAGNI because it is quite hard to envision any kind of function operating only on this interface, but … you never know.

RealFunction

Interface for real function is simple – real number in, real number out.

```
class IRealFunction : public IFunction<Real, Real>
{
public:
  virtual Real operator()(Real) const = 0;

  virtual ~IRealFunction() {}
};
```

Two implementations:

First one expects function pointer, meaning it will also accept lambda expression with function definition.

Make case for also defining std::function version … actually they will be essential for creating coordinate transformation classes that are not completely static (like spherical), but depend on some kind of parameter (angle for rotations, or matrix for general linear transformation)

```
//////////////////////////     REAL FUNCTION      ///////////////////////////////////
class RealFunction : public IRealFunction
{
  Real(*_func)(const Real);
public:
  RealFunction(Real(*inFunc)(const Real)) : _func(inFunc) {}

  Real operator()(const Real x) const { return _func(x); }
};
class RealFunctionFromStdFunc : public IRealFunction
{
  std::function<Real(const Real)> _func;
public:
  RealFunctionFromStdFunc(std::function<Real(const Real)> inFunc) : _func(inFunc) {}

  Real operator()(const Real x) const { return _func(x); }
};
```

ScalarFunction<N>

Representing scalar function, that takes vector as an input, and returns real number.

Interface

```
////////////////////////////////////////////////////////////////////////
template<int N>
class IScalarFunction : public IFunction<Real, const VectorN<Real, N>&>
{
public:
  virtual Real operator()(const VectorN<Real, N>& x) const = 0;

  virtual ~IScalarFunction() {}
};
```

Implementations

```
//////////////////////////     SCALAR FUNCTION      ///////////////////////////////////
template<int N>
class ScalarFunction : public IScalarFunction<N>
{
  Real(*_func)(const VectorN<Real, N>&);
public:
  ScalarFunction(Real(*inFunc)(const VectorN<Real, N>&)) : _func(inFunc) {}

  Real operator()(const VectorN<Real, N>& x) const { return _func(x); }
};

template<int N>
class ScalarFunctionFromStdFunc : public IScalarFunction<N>
{
  std::function<Real(const VectorN<Real, N>&)> _func;
public:
  ScalarFunctionFromStdFunc(std::function<Real(const VectorN<Real, N>&)> inFunc) : _func(inFunc) {}

  Real operator()(const VectorN<Real, N>& x) const { return _func(x); }
};
```

VectorFunction<N>

Representing vector function, that returns vector for given vector input parameter.

Interface

```
////////////////////////////////////////////////////////////////////
template<int N>
class IVectorFunction : public IFunction<VectorN<Real, N>, const VectorN<Real, N>&>
{
public:
  virtual VectorN<Real, N> operator()(const VectorN<Real, N>& x) const = 0;

  virtual ~IVectorFunction() {}
};
```

Implementations

```
//////////////////////    VECTOR FUNCTION N -> N      ////////////////////////////////
template<int N>
class VectorFunction : public IVectorFunction<N>
{
  VectorN<Real, N>(*_func)(const VectorN<Real, N>&);
public:
  VectorFunction(VectorN<Real, N>(*inFunc)(const VectorN<Real, N>&)) : _func(inFunc) {}

  VectorN<Real, N>     operator()(const VectorN<Real, N>& x) const { return _func(x); }
};

template<int N>
class VectorFunctionFromStdFunc : public IVectorFunction<N>
{
  std::function<VectorN<Real, N>(const VectorN<Real, N>&)> _func;
public:
  VectorFunctionFromStdFunc(std::function<VectorN<Real, N>(const VectorN<Real, N>&)>& inFunc)
    : _func(inFunc) {}

  VectorN<Real, N>     operator()(const VectorN<Real, N>& x) const { return _func(x); }
};
```

ParametricCurve<N>

Interfaces

Is it really needed to create this additional interface??? Hm …

```
////////////////////////////////////////////////////////////////////
template<int N>
class IRealToVectorFunction : public IFunction<VectorN<Real, N>, Real>
{
public:
  virtual VectorN<Real, N> operator()(Real x) const = 0;

  virtual ~IRealToVectorFunction() {}
};
```

General interface for parametric curve.

```
////////////////////////////////////////////////////////////////////
template<int N>
class IParametricCurve : public IRealToVectorFunction<N>
{
public:
  virtual Real getMinT() const = 0;
  virtual Real getMaxT() const = 0;

  std::vector<VectorN<Real, N>> GetTrace(double t1, double t2, int numPoints) const
  {
    std::vector<VectorN<Real, N>> ret;
    double deltaT = (t2 - t1) / (numPoints - 1);
    for (Real t = t1; t <= t2; t += deltaT)
      ret.push_back((*this)(t));
    return ret;
  }

  virtual ~IParametricCurve() {}
};
```

Implementation

```
template<int N>
class   ParametricCurve : public IParametricCurve<N>
{
  Real _minT;
  Real _maxT;
  VectorN<Real, N>(*_func)(Real);
public:
  ParametricCurve(VectorN<Real, N>(*inFunc)(Real))
    : _func(inFunc), _minT(Constants::NegativeInf), _maxT(Constants::PositiveInf) {}
  ParametricCurve(Real minT, Real maxT, VectorN<Real, N>(*inFunc)(Real))
    : _func(inFunc), _minT(minT), _maxT(maxT) {}

  Real getMinT() const { return _minT; }
  Real getMaxT() const { return _maxT; }

  virtual VectorN<Real, N> operator()(Real x) const { return _func(x); }
};
```

ParametricSurface<N>

Two different interfaces, for different kinds of surface models.

General surface

```
// complex surface, with fixed u limits, but variable w limits (dependent on u)
template<int N>
class IParametricSurface : public IFunction<VectorN<Real, N>, const VectorN<Real, 2>&>
{
public:
  virtual VectorN<Real, N> operator()(Real u, Real w) const = 0;

  virtual Real getMinU() const = 0;
  virtual Real getMaxU() const = 0;
  virtual Real getMinW(Real u) const = 0;
  virtual Real getMaxW(Real u) const = 0;

  virtual VectorN<Real, N> operator()(const VectorN<Real, 2>& coord) const
  {
    return operator()(coord[0], coord[1]);
  }

  virtual ~IParametricSurface() {}
};
```

Rectangular surface

```
// simple regular surface, defined on rectangular coordinate patch
template<int N>
class IParametricSurfaceRect : public IFunction<VectorN<Real, N>, const VectorN<Real, 2>&>
{
public:
  virtual VectorN<Real, N> operator()(Real u, Real w) const = 0;

  virtual Real getMinU() const = 0;
  virtual Real getMaxU() const = 0;
  virtual Real getMinW() const = 0;
  virtual Real getMaxW() const = 0;

  virtual VectorN<Real, N> operator()(const VectorN<Real, 2>& coord) const
  {
    return operator()(coord[0], coord[1]);
  }

  virtual ~IParametricSurfaceRect() {}
};
```

Example usage

Show examples of creating different kinds of:

- real function objects
- scalar function objects
- vector functions objects
- parametric curves
- parametric surfaces

Functions test bed

BASIC GEOMETRY IN 2D AND 3D

Defining objects that will represent concepts from 2D and 3D analytical geometry – points, vectors, lines, planes.

Points

Why special classes for points, when they are structurally same as vectors, and position is mostly defined as “radius vector”?

Example, Cartesian point in 3D

Mostly trivial and expected operations for a point:

```
class Point3Cartesian
{
private:
  Real _x, _y, _z;

public:
  Real  X() const { return _x; }
  Real& X()       { return _x; }
  Real  Y() const { return _y; }
  Real& Y()       { return _y; }
  Real  Z() const { return _z; }
  Real& Z()       { return _z; }

  Point3Cartesian() : _x(0), _y(0), _z(0) {}
  Point3Cartesian(Real x, Real y, Real z) : _x(x), _y(y), _z(z) {}

  Real  Dist(const Point3Cartesian& b) const { ... }

  bool  operator==(const Point3Cartesian& b) const { ... }
  bool  operator!=(const Point3Cartesian& b) const { ... }

  Point3Cartesian operator+(const Point3Cartesian& b) const { ... }
  Point3Cartesian operator*(Real b) { ... }
  Point3Cartesian operator/(Real b) { ... }

  friend Point3Cartesian operator*(Real a, const Point3Cartesian& b) { ... }
};
```

There’s a question of semantic validity of operator+() in this class, where adding two points is, even though mathematically precisely defined, something that looks off - namely, if you want to “add” to point, that is something you would do with a vector.

However, “adding” points is essential when we want to find middle points of a segment line or centroid of a triangle, and also for doing any kind of interpolation between two points, so it is part of the interface.

Vectors

Vector is NOT a point!

Point denotes position in space, in given coordinate system, vectors are … well, much more complex beasts

Cartesian vectors are simplest, as they are examples of *free vectors*, which are the same at every position in space, meaning that their component representation doesn't depend on position, unlike, for example vectors in spherical coordinate system.

We will deal with position-dependent kinds of vectors in Chapter 8 – Coordinate transformations, and for now cartesian vectors will do.

Example of Vector3Cartesian:

Specialized from VectorN, with Real type and dimension 3.

```
class Vector3Cartesian : public VectorN<Real, 3>
{
public:
  Real  X() const { return _val[0]; }
  Real& X()       { return _val[0]; }
  Real  Y() const { return _val[1]; }
  Real& Y()       { return _val[1]; }
  Real  Z() const { return _val[2]; }
  Real& Z()       { return _val[2]; }

  Vector3Cartesian() : VectorN<Real, 3>{ 0.0, 0.0, 0.0 } {}
  Vector3Cartesian(const VectorN<Real, 3>& b) : VectorN<Real, 3>{ b } {}
  Vector3Cartesian(Real x, Real y, Real z) : VectorN<Real, 3>{ x, y, z } {}
  Vector3Cartesian(std::initializer_list<Real> list) : VectorN<Real, 3>(list) { }
  Vector3Cartesian(const Point3Cartesian& a, const Point3Cartesian& b) { ... }

  Point3Cartesian getAsPoint() { ... }
```

Set of arithmetic operations

```
Point3Cartesian getAsPoint() { ... }

// For Cartesian vector, we will enable operator* to represent standard scalar product
Real operator*(const Vector3Cartesian& b) const { ... }

friend Vector3Cartesian operator*(const Vector3Cartesian& a, Real b) { ... }
friend Vector3Cartesian operator*(Real a, const Vector3Cartesian& b) { ... }
friend Vector3Cartesian operator/(const Vector3Cartesian& a, Real b) { ... }

friend Vector3Cartesian operator-(const Point3Cartesian& a, const Point3Cartesian& b)

friend Point3Cartesian operator+(const Point3Cartesian& a, const Vector3Cartesian& b)
friend Point3Cartesian operator-(const Point3Cartesian& a, const Vector3Cartesian& b)
```

And some more

```
bool IsParallelTo(const Vector3Cartesian& b, Real eps = 1e-15) const { ... }
bool IsPerpendicularTo(const Vector3Cartesian& b, Real eps = 1e-15) const { ... }
Real AngleToVector(const Vector3Cartesian& b) { ... }

friend Real ScalarProduct(const Vector3Cartesian& a, const Vector3Cartesian& b) { ... }
friend Vector3Cartesian VectorProd(const Vector3Cartesian& a, const Vector3Cartesian& b)
```

Lines

There are multiple ways of defining lines (TODO)

In both2D and 3D cases are specified with point, and vector representing direction, ie. representing parametric line equation.

Example Line3D

```
class Line3D
{
private:
  Point3Cartesian  _point;
  Vector3Cartesian _direction;

public:
  Line3D() {}
  // by default, direction vector is normalized to unit vector (but, it need not be such!)
  Line3D(const Point3Cartesian& pnt, const Vector3Cartesian dir) { ... }
  Line3D(const Point3Cartesian& a, const Point3Cartesian& b) { ... }

  Point3Cartesian   StartPoint() const { return _point; }
  Point3Cartesian&  StartPoint() { return _point; }

  Vector3Cartesian  Direction() const { return _direction; }
  Vector3Cartesian& Direction() { return _direction; }

  Point3Cartesian operator()(Real t) const { return _point + t * _direction; }

  bool IsPerpendicular(const Line3D& b) const { ... }
  bool IsParallel(const Line3D& b) const { ... }
```

More operations:

```
// distance between point and line
Real Dist(const Point3Cartesian& pnt) const { ... }
// distance between two lines
Real Dist(const Line3D& line) const { ... }
// distance between two lines, while also returning nearest points on both lines
Real Dist(const Line3D& line, Point3Cartesian& out_line1_pnt, Point3Cartesian& out_line2_pnt) const

// nearest point on line to given point
Point3Cartesian NearestPointOnLine(const Point3Cartesian& pnt) const { ... }

// intersection of two lines
bool Intersection(const Line3D& line, Point3Cartesian& out_inter_pnt) const { ... }

// perpendicular line that goes through givenpoint
Line3D PerpendicularLineThroughPoint(const Point3Cartesian& pnt) { ... }
```

Plane3D class

Representing plane in 3D Cartesian space, with general equation Ax + By + CZ + D = 0.

Extensive set of constructors,

```
class Plane3D
{
private:
  Real _A, _B, _C, _D;

public:
  Plane3D(const Point3Cartesian& a, const Vector3Cartesian& normal) { ... }
  Plane3D(const Point3Cartesian& a, const Point3Cartesian& b, const Point3Cartesian& c) { ... }
  // Hesse normal form
  Plane3D(Real alpha, Real beta, Real gamma, Real d) { ... }
  // segments on coordinate axes
  Plane3D(Real seg_x, Real seg_y, Real seg_z) { ... }

  static Plane3D GetXYPlane() { return Plane3D(Point3Cartesian(0, 0, 0), Vector3Cartesian(0, 0, 1)); }
  static Plane3D GetXZPlane() { return Plane3D(Point3Cartesian(0, 0, 0), Vector3Cartesian(0, 1, 0)); }
  static Plane3D GetYZPlane() { return Plane3D(Point3Cartesian(0, 0, 0), Vector3Cartesian(1, 0, 0)); }

  Real  A() const { return _A; }
  Real& A()       { return _A; }
  Real  B() const { return _B; }
  Real& B()       { return _B; }
  Real  C() const { return _C; }
  Real& C()       { return _C; }
  Real  D() const { return _D; }
  Real& D()       { return _D; }

  Vector3Cartesian  Normal() const { return Vector3Cartesian(_A, _B, _C); }
  Point3Cartesian   GetPointOnPlane() const { ... }

  void GetCoordAxisSegments(Real& outseg_x, Real& outseg_y, Real& outseg_z) { ... }
```

Basic operations between plane and points, lines, and other planes.

```
// point to plane operations
bool IsPointOnPlane(const Point3Cartesian& pnt, Real defEps = 1e-15) const { ... }
Real DistToPoint(const Point3Cartesian& pnt) const { ... }

Point3Cartesian ProjectionToPlane(const Point3Cartesian& pnt) const { ... }

// line to plane operations
bool IsLineOnPlane(const Line3D& line) const { ... }
Real AngleToLine(const Line3D& line) const { ... }
bool IntersectionWithLine(const Line3D& line, Point3Cartesian& out_inter_pnt) const { ..

// plane to plane operations
bool IsParallelToPlane(const Plane3D& plane) const { ... }
bool IsPerpendicularToPlane(const Plane3D& plane) const { ... }
Real AngleToPlane(const Plane3D& plane) const { ... }
Real DistToPlane(const Plane3D& plane) const { ... }
bool IntersectionWithPlane(const Plane3D& plane, Line3D& out_inter_line) const { ... }
```

Triangles

Each triangle has A(), B(), C() … but not enforced through interface

Making Triangle3D a ParametricSurface<3>

Boxes

Modeling surfaces & solid bodies

Two approaches

- Boundaries defined by functions
- Composed of surface polygons that (hopefully) enclose the body

Example usage

Analytical geometry examples in 2d and 3d

Creating bodies

2. Basic algorithms

Putting some algorithmic meat on our objects.

SOLVING SYSTEMS OF LINEAR EQUATIONS

General introduction

Little bit of algebra – singular matrices, rank, kernel, null space

Gauss-Jordan

Starting with the basic Gauss-Jordan elimination algorithm … THAT SHOULD NEVER BE USED!

Gauss-Jordan with pivoting

LU decomposition

Solving iteratively – Jacoby, Gauss-Seidel, SOR

NUMERICAL DERIVATION

Most of the code here is based on Boost.Math toolkit, and its differentiation routines.

Mathematics of derivation approximation

Taylor expansion and all that jazz.

Derivation routines

```
static inline const Real NDer1_h = 2 * std::sqrt(Constants::Epsilon);
static inline const Real NDer2_h = std::pow(3 * Constants::Epsilon, 1.0 / 3.0);
static inline const Real NDer4_h = std::pow(11.25 * Constants::Epsilon, 1.0 / 5.0);
static inline const Real NDer6_h = std::pow(Constants::Epsilon / 168.0, 1.0 / 7.0);
static inline const Real NDer8_h = std::pow(551.25 * Constants::Epsilon, 1.0 / 9.0);
```

First order derivation of a RealFunction

```
static Real NDer1(const IRealFunction& f, Real x, Real h, Real* error = nullptr)
{
  Real yh = f(x + h);
  Real y0 = f(x);
  Real diff = yh - y0;
  if (error)
  {
    Real ym = f(x - h);
    Real ypph = std::abs(yh - 2 * y0 + ym) / h;

    // h*|f''(x)|*0.5 + (|f(x+h)+|f(x)|) * eps/h
    *error = ypph / 2 + (std::abs(yh) + std::abs(y0)) * Constants::Epsilon / h;
  }
  return diff / h;
}
```

We have quite a few versions:

```
static Real NDer1(const IRealFunction& f, Real x, Real h, Real* error = nullptr) { ... }
static Real NDer1(const IRealFunction& f, Real x, Real* error) { ... }
static Real NDer1(const IRealFunction& f, Real x) { ... }

static Real NDer1Left(const IRealFunction& f, Real x, Real* error = nullptr) { ... }
static Real NDer1Right(const IRealFunction& f, Real x, Real* error = nullptr) { ... }
static Real NDer1Left(const IRealFunction& f, Real x, Real h, Real* error = nullptr) { ... }
static Real NDer1Right(const IRealFunction& f, Real x, Real h, Real* error = nullptr) { ... }

static Real NSecDer1(const IRealFunction& f, Real x, Real h, Real* error = nullptr) { ... }
static Real NSecDer1(const IRealFunction& f, Real x, Real* error = nullptr) { ... }

static Real NThirdDer1(const IRealFunction& f, Real x, Real h, Real* error = nullptr) { ... }
static Real NThirdDer1(const IRealFunction& f, Real x, Real* error = nullptr) { ... }
```

Calculating fourth order derivation

```
static Real NDer4(const IRealFunction& f, Real x, Real h, Real* error = nullptr)
{
  Real yh = f(x + h);
  Real ymh = f(x - h);
  Real y2h = f(x + 2 * h);
  Real ym2h = f(x - 2 * h);

  Real y2 = ym2h - y2h;
  Real y1 = yh - ymh;

  if (error)
  {
    // ...
    Real y3h = f(x + 3 * h);
    Real ym3h = f(x - 3 * h);

    // Error from fifth derivative:
    *error = std::abs((y3h - ym3h) / 2 + 2 * (ym2h - y2h) + 5 * (yh - ymh) / 2) / (30 * h);
    // Error from function evaluation:
    *error += Constants::Epsilon * (std::abs(y2h) + std::abs(ym2h) + 8 * (std::abs(ymh) + std::abs(yh))) / (12 * h)
  }
  return (y2 + 8 * y1) / (12 * h);
}
```

Fourth order (partial) derivation of ScalarFunction (we have to specify by which index we are deriving)

```
template <int N>
static Real NDer4Partial(const IScalarFunction<N>& f, int deriv_index, const VectorN<Real, N>& point, Real h, Real* error = nullptr)
{
  Real     orig_x = point[deriv_index];

  VectorN<Real, N> x{ point };
  x[deriv_index] = orig_x + h;
  Real yh = f(x);

  x[deriv_index] = orig_x - h;
  Real ymh = f(x);

  x[deriv_index] = orig_x + 2 * h;
  Real y2h = f(x);

  x[deriv_index] = orig_x - 2 * h;
  Real ym2h = f(x);

  Real y2 = ym2h - y2h;
  Real y1 = yh - ymh;

  if (error)
  {
    x[deriv_index] = orig_x + 3 * h;
    Real y3h = f(x);

    x[deriv_index] = orig_x - 3 * h;
    Real ym3h = f(x);

    *error = std::abs((y3h - ym3h) / 2 + 2 * (ym2h - y2h) + 5 * (yh - ymh) / 2) / (30 * h);
    *error += Constants::Epsilon * (std::abs(y2h) + std::abs(ym2h) + 8 * (std::abs(ymh) + std::abs(yh))) / (12 * h);
  }
  return (y2 + 8 * y1) / (12 * h);
}
```

Vector function derivation routines, fourth order

```
template <int N>
static Real NDer4Partial(const IVectorFunction<N>& f, int func_index, int deriv_index, const VectorN<Real, N>& point,
                         Real* error = nullptr) { ... }
template <int N>
static Real NDer4Partial(const IVectorFunction<N>& f, int func_index, int deriv_index, const VectorN<Real, N>& point, Real h,
                         Real* error = nullptr) { ... }
template <int N>
static VectorN<Real, N> NDer4PartialByAll(const IVectorFunction<N>& f, int func_index, const VectorN<Real, N>& point,
                                          VectorN<Real, N>* error = nullptr) { ... }
template <int N>
static VectorN<Real, N> NDer4PartialByAll(const IVectorFunction<N>& f, int func_index, const VectorN<Real, N>& point, Real h,
                                          VectorN<Real, N>* error = nullptr) { ... }
template <int N>
static MatrixNM<Real, N, N> NDer4PartialAllByAll(const IVectorFunction<N>& f, const VectorN<Real, N>& point,
                                                 MatrixNM<Real, N, N>* error = nullptr) { ... }
template <int N>
static MatrixNM<Real, N, N> NDer4PartialAllByAll(const IVectorFunction<N>& f, const VectorN<Real, N>& point, Real h,
                                                 MatrixNM<Real, N, N>* error = nullptr) { ... }
```

ParametricCurve derivations

```
template <int N>
static VectorN<Real, N> NDer4(const IParametricCurve<N>& f, Real t, Real* error = nullptr) { ... }

template <int N>
static VectorN<Real, N> NDer4(const IParametricCurve<N>& f, Real t, Real h, Real* error = nullptr) { ..

template <int N>
static VectorN<Real, N> NSecDer4(const IParametricCurve<N>& f, Real t, Real* error = nullptr) { ... }

template <int N>
static VectorN<Real, N> NSecDer4(const IParametricCurve<N>& f, Real t, Real h, Real* error = nullptr) {


template <int N>
static VectorN<Real, N> NThirdDer4(const IParametricCurve<N>& f, Real t, Real* error = nullptr) { ... }

template <int N>
static VectorN<Real, N> NThirdDer4(const IParametricCurve<N>& f, Real t, Real h, Real* error = nullptr)
```

Automatic differentiation

Short overview of basic AD implementation

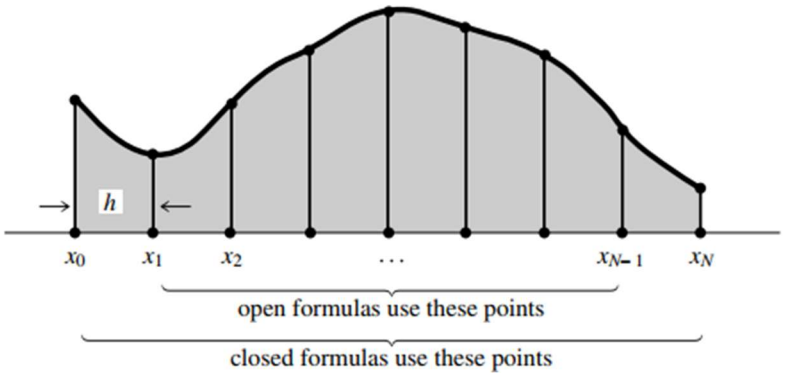
NUMERICAL INTEGRATION

We want so solve this

$$I = \int_a^b f(x)dx$$

For a given function f, and limits a and b.

Open vs closed formulas.



Basic trapezoidal rule for approximation in single interval.

$$\int_{x_0}^{x_1} f(x)dx = h\left[\frac{1}{2}f_0 + \frac{1}{2}f_1\right] \quad + O(h^3 f'')$$

Simpson's rule

$$\int_{x_0}^{x_2} f(x)dx = h\left[\frac{1}{3}f_0 + \frac{4}{3}f_1 + \frac{1}{3}f_2\right] \quad + O(h^5 f^{(4)})$$

Extended trapezoidal rule.

$$\int_{x_0}^{x_{N-1}} f(x)dx = h\left[\frac{1}{2}f_0 + f_1 + f_2 + \cdots + f_{N-2} + \frac{1}{2}f_{N-1}\right] \quad + O\left(\frac{(b-a)^3 f''}{N^2}\right)$$

Trapezoidal integrator

Gauss-Legendre integration

Integrating in 2D

Integrating in 3D

INTERPOLATING FUNCTIONS

PolynomInterpFunc

SplineInterpFunc

ParametricCurveSplineInterp

ROOT FINDING

Bracketing roots

Bisection

Newton-Raphson algorithm

3. Visualization, anyone?

Using Qt

Ideal for open-source projects

Widgets, enabling interactive application

2D animation for collision simulator

Creating simple application for visualization of moving circles within given rectangle.

We will be extending this in Chapter 4, for collision simulator.

Using FLTK

Simple to use, and cross-platform, FLTK is another option, especially if Qt open source (or commercial) license is not suitable.

Visualizing real function

Short example of visualizing real function in some interval.

Using Python with VTK binding?

Matplotlib is beautiful piece of software, and by creating interface between our C++ code and Python, we can efficiently utilize it.

Based on book “Introduction to numerical programming” by Titus Adrian Beu and toolkit presented there.

Contour plot

USING GNUPLOT?

To do, or not to do?

It is cross-platform, and powerful in its visualization capabilities

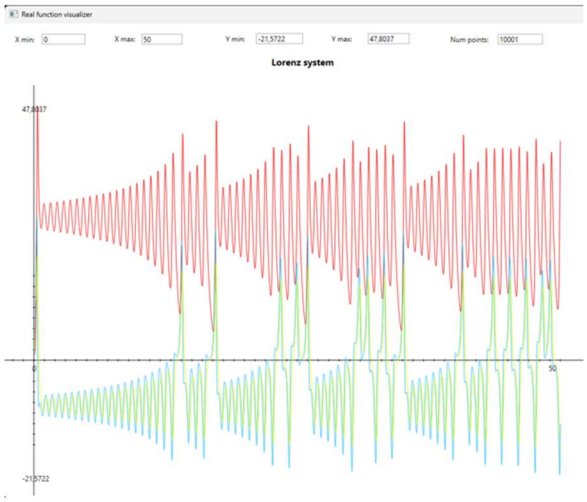
USING .NET WPF

Unlike previous visualization solutions, this one is available only for Windows, as it relies on mighty Windows Presentation Foundation framework for visualization.

Also, it is similar in its usage pattern to GnuPlot where we need to export all relevant data that needs visualizing in a file, and then give that file as an input to WPF visualizing application.

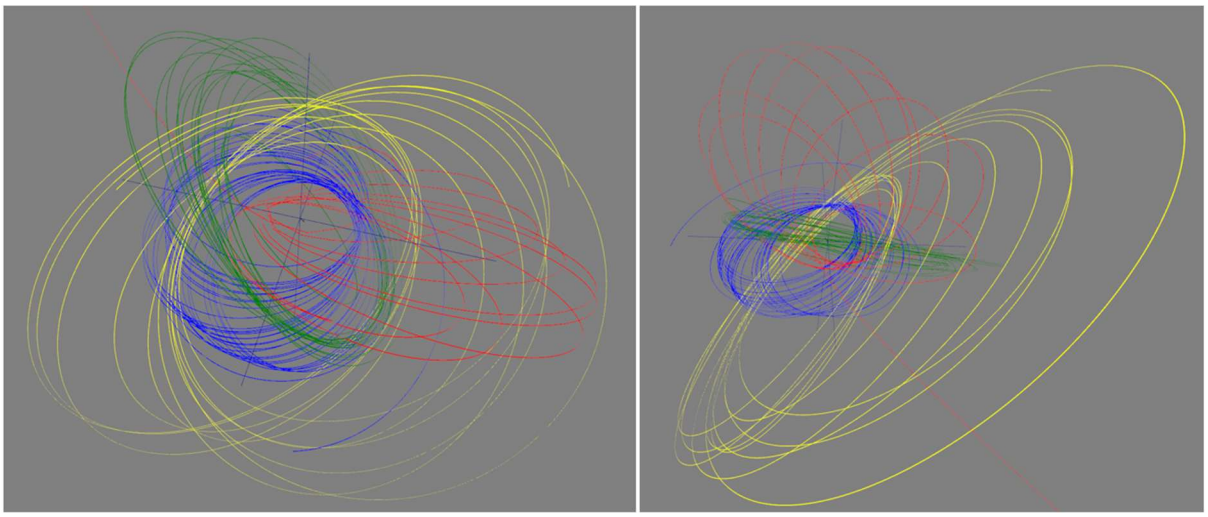
Visualizing real functions

Solution of Lorentz system.



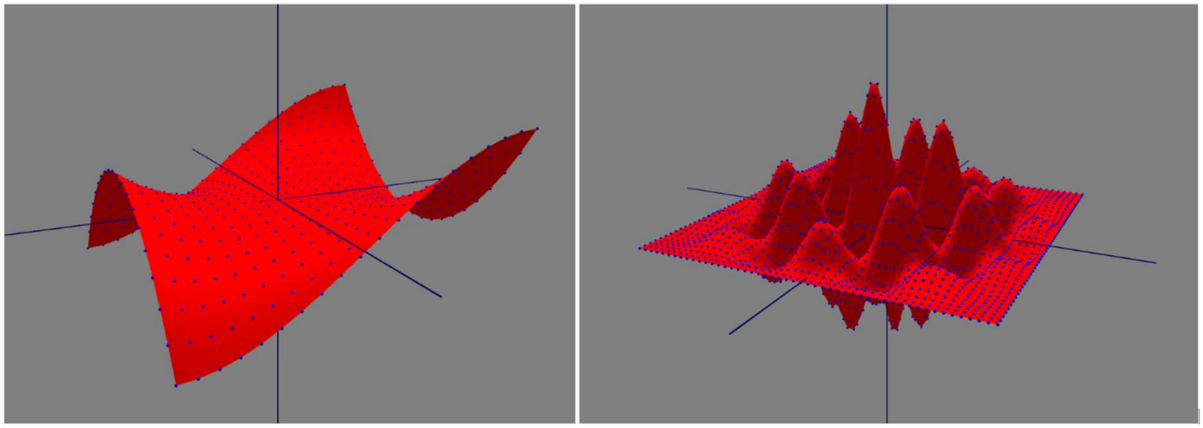
Visualizing parametric curves in 2D and 3D

Visualizing 3D trajectories for 5-body gravity problem

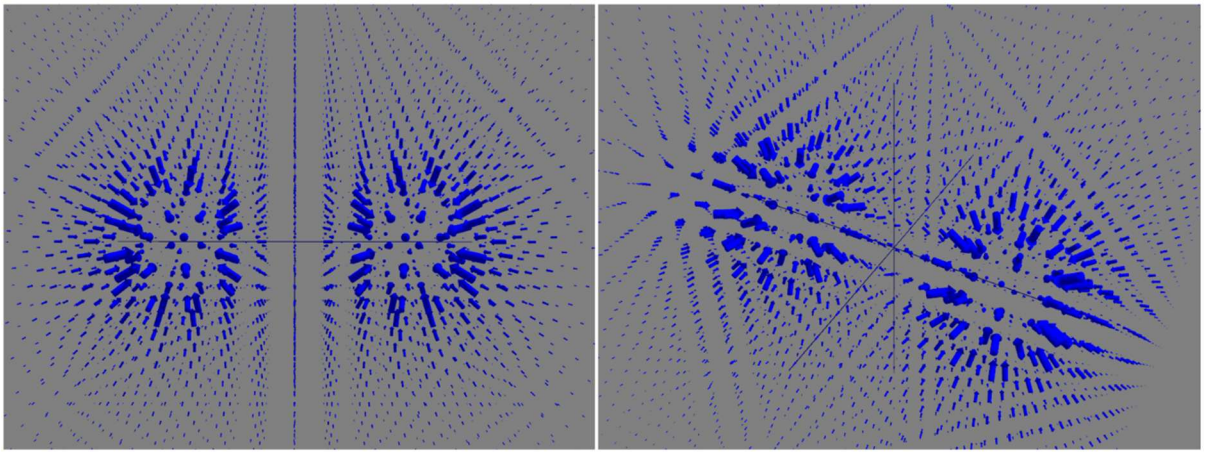


Implementing animation?

Visualizing surfaces



Visualizing 3D vector field



Visualization objects in C++ for WPF visualizer

Set of objects that removes from user need for manually saving data in a file, and then giving that file as parameter.

Basically, it uses existing Serializer object that can serialize to a file values for different kinds of functions, defines some constants with paths to visualizing applications, and ties all that in a set of simple static functions

```
class Visualizer
{
    static inline std::string _pathResultFiles{ GLOB_PATH_ResultFiles };

    static inline std::string _pathRealFuncViz{ GLOB_PATH_RealFuncViz };
    static inline std::string _pathSurfaceViz{ GLOB_PATH_SurfaceViz };
    static inline std::string _pathParametricCurveViz{ GLOB_PATH_ParametricCurveViz };
    static inline std::string _pathVectorFieldViz{ GLOB_PATH_VectorFieldViz };

public:
    static void VisualizeRealFunction(const IRealFunction& f, std::string title, Real x1, Real x2, int numPoints, std::string fileName)
    {
        std::string name = _pathResultFiles + fileName;
        Serializer::SaveRealFuncEquallySpacedDetailed(f, title, x1, x2, numPoints, name);

#if defined(MML_PLATFORM_WINDOWS)
        std::string command = _pathRealFuncViz + " " + name;
        system(command.c_str());
#else
        std::cout << "VisualizeRealFunction: Not implemented for this OS" << std::endl;
#endif
    }
```

4. From colliding mechanical balls to gas laws

Embarking on our journey with some 17th and 18th century physics.

Tasks at hand:

- Given positions and initial velocities of N simple mechanical balls, confined to 2D or 3D container, calculate their positions in time.
- Relate to gas laws

PHYSICS – COLLIDING MECHANICAL BALLS

Starting with basics of physics

We'll need First newton law, and law of conservation of energy together with law of conservation of momentum.

One-dimensional case

TODO - Two balls, pictured on a line.

Conservation of momentum:

$$m_A v_{A1} + m_B v_{B1} = m_A v_{A2} + m_B v_{B2}.$$

Conservation of energy:

$$\frac{1}{2} m_A v_{A1}^2 + \frac{1}{2} m_B v_{B1}^2 = \frac{1}{2} m_A v_{A2}^2 + \frac{1}{2} m_B v_{B2}^2.$$

When solved, gives:

$$\begin{aligned} v_{A2} &= \frac{m_A - m_B}{m_A + m_B} v_{A1} + \frac{2m_B}{m_A + m_B} v_{B1} \\ v_{B2} &= \frac{2m_A}{m_A + m_B} v_{A1} + \frac{m_B - m_A}{m_A + m_B} v_{B1}. \end{aligned}$$

Center of mass frame doesn't change!

Two-dimensional case

Dependent on the point of collision, and after lengthy calculation, in an angle-free representation, the changed velocities are computed using the centers $\mathbf{x}_1$ and $\mathbf{x}_2$ at the time of contact as:

$$\mathbf{v}_1' = \mathbf{v}_1 - \frac{2m_2}{m_1 + m_2} \frac{\langle \mathbf{v}_1 - \mathbf{v}_2, \mathbf{x}_1 - \mathbf{x}_2 \rangle}{\|\mathbf{x}_1 - \mathbf{x}_2\|^2} (\mathbf{x}_1 - \mathbf{x}_2),$$
$$\mathbf{v}_2' = \mathbf{v}_2 - \frac{2m_1}{m_1 + m_2} \frac{\langle \mathbf{v}_2 - \mathbf{v}_1, \mathbf{x}_2 - \mathbf{x}_1 \rangle}{\|\mathbf{x}_2 - \mathbf{x}_1\|^2} (\mathbf{x}_2 - \mathbf{x}_1)$$

Based on these equations, we can easily implement calculations of velocity vectors for two balls after collision:

```
// https://en.wikipedia.org/wiki/Elastic_collision - calculating new velocities after collision
double   m1 = ball1.Mass(), m2 = ball2.Mass();

Vec2Cart v1(ball1.V()), v2(ball2.V());

Vec2Cart v1_v2(v1 - v2);
Vec2Cart x1_x2(x2, x1);

Vec2Cart v1_new = v1 - 2 * m2 / (m1 + m2) * (v1_v2 * x1_x2) / POW2(x1_x2.NormL2()) * Vec2Cart(x2, x1);
Vec2Cart v2_new = v2 - 2 * m1 / (m1 + m2) * (v1_v2 * x1_x2) / POW2(x1_x2.NormL2()) * Vec2Cart(x1, x2);

ball1.V() = v1_new;
ball2.V() = v2_new;

// adjusting new ball positions
ball1.Pos() = x1 + ball1.V() * (dt - tCollision);
ball2.Pos() = x2 + ball2.V() * (dt - tCollision);
```

DOING A 2D SIMULATION - COLLISIONSIMULATOR2D

Building a simple collision simulator.

Starting with a model of 2D ball.

```
struct Ball2D
{
private:
  double _mass;
  double _radius;
  Point2Cartesian _position;
  Vector2Cartesian _velocity;

public:
  Ball2D(double mass, double radius, const Point2Cartesian& position,
         const Vector2Cartesian& velocity) { ... }

  double  Mass() const { return _mass; }
  double& Mass() { return _mass; }

  double  Rad() const { return _radius; }
  double& Rad() { return _radius; }

  Point2Cartesian  Pos() const { return _position; }
  Point2Cartesian& Pos() { return _position; }

  Vector2Cartesian  V() const { return _velocity; }
  Vector2Cartesian& V() { return _velocity; }
};
```

Container for our balls.

Simple rectangle, with bottom left corner at point (0,0), with given width and height.

```
struct Container2D
{
  double _width;
  double _height;

  std::vector<Ball2D> _balls;

  Container2D() : _width(1000), _height(1000) {}
  Container2D(double width, double height) : _width(width), _height(height) {}

  // add body
  void AddBall(const Ball2D& body) { ... }

  // get body
  Ball2D& Ball(int i) { ... }

  // check if ball is out of bounds and handle it
  void CheckAndHandleOutOfBounds(int ballIndex) { ... }
};
```

Where CheckAndHandleOutOfBounds() function is crucial:

```
void CheckAndHandleOutOfBounds(int ballIndex)
{
  const Ball2D& ball = ball;

  // left wall collision
  if (ball.Pos().X() < ball.Rad() && ball.V().X() < 0)
  {
    ball.Pos().X() = ball.Rad() + (ball.Rad() - ball.Pos().X()); // Get back to box!
    ball.V().X() *= -1;
  }
  // right wall collision
  if (ball.Pos().X() > _width - ball.Rad() && ball.V().X() > 0)
  {
    ball.Pos().X() -= (ball.Pos().X() + ball.Rad()) - _width;
    ball.V().X() *= -1;
  }
  // bottom wall collision
  if (ball.Pos().Y() < ball.Rad() && ball.V().Y() < 0)
  {
    ball.Pos().Y() = ball.Rad() + (ball.Rad() - ball.Pos().Y());
    ball.V().Y() *= -1;
  }
  // top wall collision
  if (ball.Pos().Y() > _height - ball.Rad() && ball.V().Y() > 0)
  {
    ball.Pos().Y() -= (ball.Pos().Y() + ball.Rad()) - _height;
    ball.V().Y() *= -1;
  }
}
```

And finally, CollisionSimulator2D class, implementing simulator.

```
class CollisionSimulator2D
{
  Container2D _box;

public:
  CollisionSimulator2D() { }
  CollisionSimulator2D(const Container2D& box) : _box(box) {}

  double DistBalls(int i, int j) { ... }

  bool HasBallsCollided(int i, int j) { ... }

  void SimulateOneStep(double dt)
  {
    // ...
    int NumBalls = _box._balls.size();

    // first, update all ball's positions, and handle out of bounds
    for (int i = 0; i < NumBalls; i++)
    {
      _box._balls[i].Pos() = _box._balls[i].Pos() + _box._balls[i].V() * dt;

      _box.CheckAndHandleOutOfBounds(i);
    }

    // check for collisions, and handle it if there is one
    for (int m = 0; m < NumBalls - 1; m++) {
      for (int n = m + 1; n < NumBalls; n++)
      {
        if (HasBallsCollided(m, n)) { ... }
      }
    }
  }
};
```

Visualizing container with balls with Qt

TODO

3D SIMULATION

Implementation is the same, only using Vector3Cartesian!

Visualizing with WPF?

PHYSICS – IDEAL GAS

Model of colliding balls in elastic collision is fairly good approximation for ideal gas.

Little bit of formulas.

SIMULATING IDEAL GAS

Developed collision simulator can be used to verify basic gas laws, as our mechanical balls model represents most of the ideal gas approximations.

Calculating pressure by summing momentum transferred to walls during collisions

Calculating temperature from average kinetic energy of balls

Verifying $p V = n R T$ gas equation

PISTON SIMULATION

Cylinder with movable wall in the middle

What happens if we inject highly energetic balls into one side?

Could we simulate chemical reactions?

- When different types of “molecules” collide, there is released energy, which translates to higher velocities after “collision”

IMPROVING EFFICIENCY FOR LARGE NUMBER OF BALLS

Implemented algorithm scales as $O(N^2)$!

Feasible for under 1000 balls.

What can we do if we want to simulate one million balls?

5. Pendulum - Newton laws and ODE solvers

Introducing forces … and those kings of numerical simulation, ODE solvers.

Tasks at hand:

- Introduce pendulum as one of the simplest physical systems
- Introduce numerical ODE solvers and calculate exact motion of pendulum
- Compare obtained solutions with analytical one
- What if we add air resistance?

PENDULUM PHYSICS

TODO – intro to pendulum

Applying Newton second law to tangential component, we get

$$F = -mg\sin\theta = ma,$$
$$a = -g\sin\theta,$$

The negative sign on the right-hand side means that θ and a always point in opposite directions

This linear acceleration a along the red axis can be related to the change in angle θ by the arc length formulas; s is arc length:

$$s = \ell\theta,$$
$$v = \frac{ds}{dt} = \ell\frac{d\theta}{dt},$$
$$a = \frac{d^2s}{dt^2} = \ell\frac{d^2\theta}{dt^2},$$

Giving our equation of motion

$$\ell\frac{d^2\theta}{dt^2} = -g\sin\theta,$$
$$\frac{d^2\theta}{dt^2} + \frac{g}{\ell}\sin\theta = 0.$$

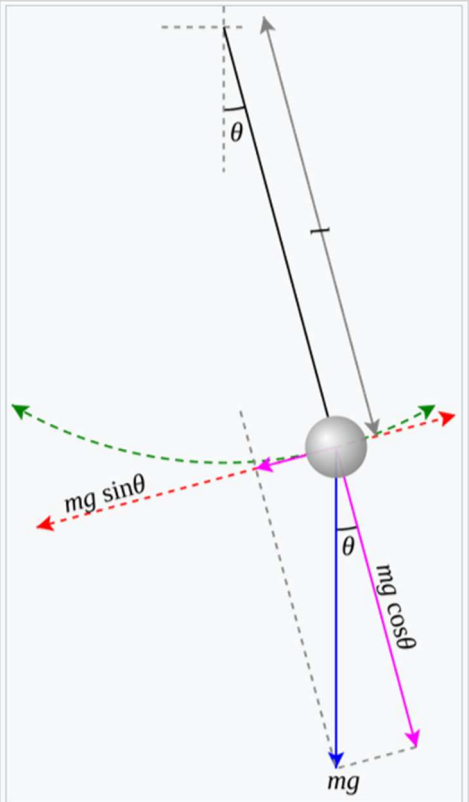


Figure 1. Force diagram of a simple gravity pendulum.

Picture from Wikipedia.

Exact equation of motion

Linear approximation for small angles

How can we calculate exact values?

SOLVING ODES NUMERICALLY

Euler method

Midpoint method

Runge-Kutta methods

Adaptive step size methods

IMPLEMENTING ODE SOLVERS IN C++

ODESystem class

Basic interface, used for modelling system of ordinary differential equations.

```
class IODESystem
{
public:
  virtual int   getDim() const = 0;
  virtual void  derivs(const Real t, const Vector<Real> &x, Vector<Real> &dxdt) const = 0;
};
```

You can use it to create your own ODE system, by inheriting this interface in your class and providing two virtual methods.

TODO – example ODE from introduction, but for now, Pendulum example from chapter 5 will do.

```
class PendulumODE : public IODESystem
{
  Real _Length;
public:
  PendulumODE(Real length) : _Length(length) {}

  int  getDim() const override { return 2; }
  void derivs(const Real t, const MML::Vector<Real> &x, MML::Vector<Real> &dxdt) const override
  {
    dxdt[0] = x[1];
    dxdt[1] = -9.81 / _Length * sin(x[0]);
  }
};
```

If you already have a (static) function ready with derivatives calculation, or maybe your system equations can be easily coded with simple lambda, you can use provided ODESystem class.

```
class ODESystem : public IODESystem
{
protected:
  int _dim;
  void (*_func)(Real, const Vector<Real>&, Vector<Real>&);

public:
  ODESystem() : _dim(0), _func(nullptr) { }
  ODESystem(int n, void (*inFunc)(Real, const Vector<Real>&, Vector<Real>&))
    : _dim(n), _func(inFunc) { }

  int getDim() const { return _dim; }
  void derivs(const Real x, const Vector<Real>& y, Vector<Real>& dydx) const { ... }
};
```

Example of pendulum system definition using lambda.

```
void Demo_ExactPendulum()
{
  ODESystem pendSys(2, [](Real t, const Vector<Real>& x, Vector<Real>& dxdt)
    {
      Real Length = 1.0;
      dxdt[0] = x[1];
      dxdt[1] = -9.81 / Length * sin(x[0]);
    });
```

Created object pendSys is ready to be supplied wherever IODESystem reference is expected.

Important thing to note is that in case with lambda definition, Length parameter is hard-coded within lambda, and can't be changed in run-time!

RungeKutta4_FixedStep

Calculating step

```
class RungeKutta4_FixedStep
{
public:
  /* ... */
  void calcStep(const Vector<Real>& y_start, const Vector<Real>& dydx, const Real x, const Real h,
                Vector<Real>& yout, const IODESystem& odeSystem)
  {
    int i, n = odeSystem.getDim();
    Vector<Real> dy_mid(n), dy_temp(n), y_temp(n);

    Real xh, hh, h6;
    hh = h * 0.5;
    h6 = h / 6.0;
    xh = x + hh;

    for (i = 0; i < n; i++)                       // First step
      y_temp[i] = y_start[i] + hh * dydx[i];

    odeSystem.derivs(xh, y_temp, dy_temp);        // Second step

    for (i = 0; i < n; i++)
      y_temp[i] = y_start[i] + hh * dy_temp[i];

    odeSystem.derivs(xh, y_temp, dy_mid);         // Third step

    for (i = 0; i < n; i++) {
      y_temp[i] = y_start[i] + h * dy_mid[i];
      dy_mid[i] += dy_temp[i];
    }

    odeSystem.derivs(x + h, y_temp, dy_temp);     // Fourth step

    for (i = 0; i < n; i++)
      yout[i] = y_start[i] + h6 * (dydx[i] + dy_temp[i] + 2.0 * dy_mid[i]);
  }
```

Performing integration.

```cpp
// For given numSteps, ODESystemSolution will have numSteps+1 values!
ODESystemSolution integrate(const IODESystem& odeSystem, const Vector<Real>& initCond, Real x1, Real x2, int numSteps)
{
  int   dim = odeSystem.getDim();

  ODESystemSolution sol(x1, x2, dim, numSteps);
  Vector<Real>      y(initCond), y_out(dim), dydx(dim);

  sol.fillValues(0, x1, y);

  Real x = x1;
  Real h = (x2 - x1) / numSteps;

  for (int k = 1; k <= numSteps; k++) {
    odeSystem.derivs(x, y, dydx);

    calcStep(y, dydx, x, h, y_out, odeSystem);

    x += h;

    y = y_out;
    sol.fillValues(k, x, y);
  }

  return sol;
}
```

RungeKutta4_CashKarpAdaptive

Example of simple adaptive size algorithm

Generalizing steppers with BaseStepper class

General class for adaptive step methods

Main challenge –

Stepper

- Odradi korak … kako najbolje može
- Vraća idući h

ODESystemSolution class

ODESolver class as master integrator

- Templated on stepper
- Gets ODESystem as input

- Produces ODESystemSolution

SOLVING PENDULUM

Defining ODESystem class representing pendulum

```
class PendulumODE : public IODESystem
{
  Real _Length;
public:
  PendulumODE(Real length) : _Length(length) {}

  int  getDim() const override { return 2; }
  void derivs(const Real x, const MML::Vector<Real>& y, MML::Vector<Real>& dydx) const override
  {
    dydx[0] = y[1];
    dydx[1] = -9.81 / _Length * sin(y[0]);
  }
};
```

Using fixed step-size and adaptive step-size RK solvers to solve it.

```
PendulumODE     sys = PendulumODE(1.0);
Vector<Real>    initCond{ 0.5, 0.0 };

RungeKutta4_FixedStep   rkdumb;
ODESystemSolution sol = rkdumb.integrate(sys, initCond, 0.0, 5.0, 20);

std::cout << "**********    Runge-Kutta 4th order - Dumb    ********\n";
std::cout << "x values:\n";    sol._xval.Print(std::cout, 7, 3); std::cout << std::endl;
std::cout << "y values: - ";   sol._yval.Print(std::cout, 7, 3);

RungeKutta4_CashKarpAdaptive    rkNR2;
int nok, nbad;
const double h1 = 0.01, hmin = 0.0;
ODESystemSolution sol2 = rkNR2.integrate(sys, initCond, 0.0, 5.0, 20, 0.1, 1e-04, h1, hmin, nok, nbad);

std::cout << "\n\n**********    Runge-Kutta 4th order - stepper    ********\n";
std::cout << "x values:\n";    sol2._xval.Print(std::cout, 7, 3); std::cout << std::endl;
std::cout << "y values: - ";   sol2._yval.Print(std::cout, 7, 3);
```

LONG TERM SIMULATION

Need for symplectic integrators, that preserve phase space volume

ADDING AIR RESISTANCE

Basically, it is a dumped oscillating system

6. Spherical and double pendulum – working with Lagrangians

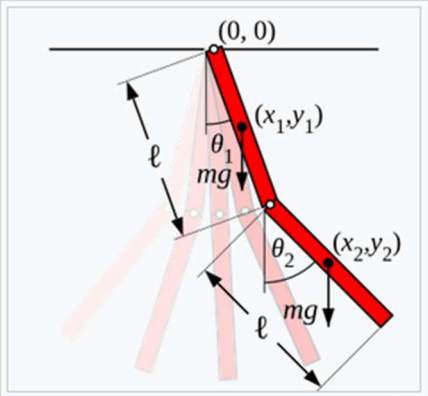
Going all-in with Lagrangian formulation of classical mechanics.

Tasks at hand:

- Introduce basics of Lagrangian formulation of classical mechanics
- Spherical pendulum as an example

PHYSICS – LAGRANGIAN FORMULATION IN CLASSICAL MECHANICS

PHYSICS - DOUBLE PENDULUM



Double compound pendulum

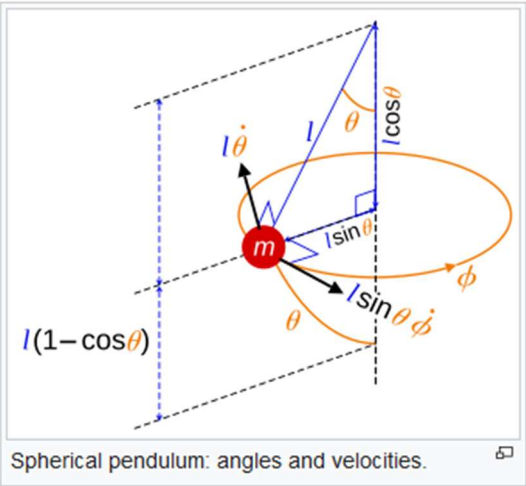
After lengthy analysis, we get equation of motion in theta1 and theta2.

$$\tfrac{1}{3}\ell\ddot{\theta}_2 + \tfrac{1}{2}\ell\ddot{\theta}_1\cos(\theta_1-\theta_2) - \tfrac{1}{2}\ell\dot{\theta}_1^2\sin(\theta_1-\theta_2) + \tfrac{1}{2}g\sin\theta_2 = 0.$$

Which, when simplified to system of first order differential equations gives this:

TODO!!!

SPHERICAL PENDULUM



Spherical pendulum: angles and velocities.

Equation of motion for theta angle

$$\ddot{\theta} = \sin\theta\cos\theta\dot{\phi}^2 - \frac{g}{l}\sin\theta$$

$$\ddot{\phi}\,\sin\theta = -2\,\dot{\theta}\,\dot{\phi}\,\cos\theta.$$

7. Hitting a ball with a baseball bat

Working it all the way for real situation.

Tasks at hand:

- What happens when we hit a baseball with a baseball bat?
- Adding air resistance
- Adding effect of drag
- Adding effect of spin

VACUUM SOLUTION

AIR RESISTANCE

EFFECT OF BASEBALL PROPERTIES - DRAG

EFFECT OF SPIN

8. Central potential – gravity field

Investigating that all-present force in our lives … gravity.

Tasks at hand:

- Verify Kepler laws in central potential
- Path integrals for work and potential
- Simulate gravity within Solar System.

PHYSICS OF GRAVITATIONAL FIELD

Bazične formule centralnog potencijala, Keplerovi zakoni

Verificirati numerički simulacijom two-body problem

Ali, standardni RungeKutta neće biti baš dobar!

Trebati će nam symplectic solvers … u idućem poglavlju

FIELD OPERATIONS

Gravity is an excellent example of a simple **field**.

Contour plot of gravity potential as basis for gradient definition

Gradient

Divergence

Curl

Laplacian

Implementation in C++

Scalar field operations – gradient and Laplacian

```
namespace ScalarFieldOperations
{
  // ...
  template<int N>
  static VectorN<Real, N> Gradient(IScalarFunction<N>& scalarField, const VectorN<Real, N>& pos,
                                   const MetricTensorField<N>& metricTensorField) { ... }

  template<int N>
  static Real Divergence(const IVectorFunction<N>& vectorField, const VectorN<Real, N>& pos,
                         const MetricTensorField<N>& metricTensorField) { ... }

  // ...
  template<int N>
  static VectorN<Real, N> GradientCart(const IScalarFunction<N>& scalarField, const VectorN<Real, N>& pos)
  template<int N>
  static VectorN<Real, N> GradientCart(const IScalarFunction<N>& scalarField, const VectorN<Real, N>& pos,
                                       int der_order) { ... }

  static Vec3Sph GradientSpher(const IScalarFunction<3>& scalarField, const Vec3Sph& pos) { ... }
  static Vec3Sph GradientSpher(const IScalarFunction<3>& scalarField, const Vec3Sph& pos,
                               int der_order) { ... }

  static Vec3Cyl GradientCyl(const IScalarFunction<3>& scalarField, const Vec3Cyl& pos) { ... }
  static Vec3Cyl GradientCyl(const IScalarFunction<3>& scalarField, const Vec3Cyl& pos,
                             int der_order) { ... }

  // ...
  template<int N>
  static Real LaplacianCart(const IScalarFunction<N>& scalarField, const VectorN<Real, N>& pos) { ... }
  static Real LaplacianSpher(const IScalarFunction<3>& scalarField, const Vec3Sph& pos) { ... }
  static Real LaplacianCyl(const IScalarFunction<3>& scalarField, const Vec3Cyl& pos) { ... }
};
```

Calculation of a gradient in spherical coordinates

```
static Vec3Sph GradientSpher(const IScalarFunction<3>& scalarField, const Vec3Sph& pos)
{
  Vector3Spherical ret = Derivation::DerivePartialAll<3>(scalarField, pos, nullptr);

  ret[1] = ret[1] / pos[0];
  ret[2] = ret[2] / (pos[0] * sin(pos[1]));

  return ret;
}
```

VectorField operations – divergence & curl

```
namespace VectorFieldOperations
{
  // ...
  template<int N>
  static Real DivCart(const IVectorFunction<N>& vectorField, const VectorN<Real, N>& pos) { ...
  static Real DivSpher(const IVectorFunction<3>& vectorField, const VectorN<Real, 3>& x) { ...
  static Real DivCyl(const IVectorFunction<3>& vectorField, const VectorN<Real, 3>& x) { ... }

  // ...
  static Vec3Cart CurlCart(const IVectorFunction<3>& vectorField, const VectorN<Real, 3>& pos)
  static Vec3Sph  CurlSpher(const IVectorFunction<3>& vectorField, const VectorN<Real, 3>& pos)
  static Vec3Cyl  CurlCyl(const IVectorFunction<3>& vectorField, const VectorN<Real, 3>& pos) {
};
```

Calculating divergence in spherical coordinates.

```
static Real DivSpher(const IVectorFunction<3>& vectorField, const VectorN<Real, 3>& x)
{
  VectorN<Real, 3> vals = vectorField(x);

  VectorN<Real, 3> derivs;
  for (int i = 0; i < 3; i++)
    derivs[i] = Derivation::DeriveVecPartial<3>(vectorField, i, i, x, nullptr);

  Real div = 0.0;
  div += 1 / (x[0] * x[0]) * (2 * x[0] * vals[0] + x[0] * x[0] * derivs[0]);
  div += 1 / (x[0] * sin(x[1])) * (cos(x[1]) * vals[1] + sin(x[1]) * derivs[1]);
  div += 1 / (x[0] * sin(x[1])) * derivs[2];

  return div;
}
```

Calculating curl

```
static Vec3Cart CurlCart(const IVectorFunction<3>& vectorField, const VectorN<Real, 3>& pos)
{
  Real dzdy = Derivation::DeriveVecPartial<3>(vectorField, 2, 1, pos, nullptr);
  Real dydz = Derivation::DeriveVecPartial<3>(vectorField, 1, 2, pos, nullptr);

  Real dxdz = Derivation::DeriveVecPartial<3>(vectorField, 0, 2, pos, nullptr);
  Real dzdx = Derivation::DeriveVecPartial<3>(vectorField, 2, 0, pos, nullptr);

  Real dydx = Derivation::DeriveVecPartial<3>(vectorField, 1, 0, pos, nullptr);
  Real dxdy = Derivation::DeriveVecPartial<3>(vectorField, 0, 1, pos, nullptr);

  Vector3Cartesian curl{ dzdy - dydz, dxdz - dzdx, dydx - dxdy };

  return curl;
}
static Vec3Sph  CurlSpher(const IVectorFunction<3>& vectorField, const VectorN<Real, 3>& pos)
{
  VectorN<Real, 3> vals = vectorField(pos);

  Real dphidtheta = Derivation::DeriveVecPartial<3>(vectorField, 2, 1, pos, nullptr);
  Real dthetadphi = Derivation::DeriveVecPartial<3>(vectorField, 1, 2, pos, nullptr);

  Real drdphi = Derivation::DeriveVecPartial<3>(vectorField, 0, 2, pos, nullptr);
  Real dphidr = Derivation::DeriveVecPartial<3>(vectorField, 2, 0, pos, nullptr);

  Real dthetadr = Derivation::DeriveVecPartial<3>(vectorField, 1, 0, pos, nullptr);
  Real drdtheta = Derivation::DeriveVecPartial<3>(vectorField, 0, 1, pos, nullptr);

  Vector3Spherical ret;
  const Real& r = pos[0];
  const Real& theta = pos[1];
  const Real& phi = pos[2];

  ret[0] = 1 / (r * sin(theta)) * (cos(theta) * vals[2] + sin(theta) * dphidtheta - dthetadphi);
  ret[1] = 1 / r * (1 / sin(theta) * drdphi - vals[2] - r * dphidr);
  ret[2] = 1 / r * (vals[1] + r * dthetadr - drdtheta);

  return ret;
}
```

PATH INTEGRATION

Calculating work between two points along different curves connecting them, and verify with potential calculation

SIMULATING GRAVITY IN SOLAR SYSTEM

Setup of all planet orbits and simulation of satellite motion through it (Voyager?).

GRAVITATIONAL SLINGSHOT – HOW IT WORKS?

9. Simulating gravity properly in N-body problem

Deep dive with gravity simulation.

Tasks at hand:

- Numerically simulate N-body problem
- Symplectic integrators

NEED FOR SYMPLECTIC ODE SOLVERS

In time independent Hamiltonian system, the energy and the phase space volume are conserved and special integration methods have to be applied in order to ensure these conservation laws.

Runge-Kutta-Nystroem solvers

SIMULATING N-BODY GRAVITATIONAL PROBLEM

All bodies interact and … well, physics of N-body gravity problem is complicated, but we can always simulate.

Using symplectic integrators!

Visualizing fields

10. Coordinate transformations

Contravariant and covariant vectors … and all that jazz.

Tasks at hand:

- Modelling general coordinate transformations in C++
- Implement various transformations
- Oblique systems and difference between contravariant and covariant vectors

TRANSFORMATION OF COORDINATES

General transformation of coordinates:

It is assumed we also have an inverse transformation

Rotations in 2D

Orthogonal transformations

Curvilinear

Spherical

Mathematical and physical convention in ordering coordinates.

Cylindrical

Oblique Cartesian coordinate system

Dual basis

TRANSFORMING VECTORS

Covariant and contravariant vectors

Vector3Spherical

Vector3Cylindrical

IMPLEMENTATIONS IN C++

We define two basic interfaces.

Why inheriting from IVectorFunction? Because every coordinate transformation is actually defined through vector function – function that takes vector of original coordinates, and returns vector of transformed coordinates.

```
template<typename VectorFrom, typename VectorTo, int N>
class ICoordTransf : public IVectorFunction<N>
{
public:
  virtual       VectorTo            transf(const VectorFrom& in) const = 0;
  virtual const IScalarFunction<N>& coordTransfFunc(int i) const = 0;

  virtual ~ICoordTransf() {}
};
```

For transformations that have an inverse, we specialize original interface, requiring

```
template<typename VectorFrom, typename VectorTo, int N>
class ICoordTransfWithInverse : public virtual ICoordTransf<VectorFrom, VectorTo, N>
{
public:
  virtual       VectorFrom          transfInverse(const VectorTo& in) const = 0;
  virtual const IScalarFunction<N>& inverseCoordTransfFunc(int i) const = 0;

  virtual ~ICoordTransfWithInverse() {}
};
```

We need explicit form of each transformation function, so we can do mathematical operations on those functions.

Then we create two abstract classes,

```
template<typename VectorFrom, typename VectorTo, int N>
class CoordTransf : public virtual ICoordTransf<VectorFrom, VectorTo, N>
{
public:
  // inherited from IVectorFunction
  VectorN<Real, N> operator()(const VectorN<Real, N>& x) const
  {
    VectorN<Real, N> ret;
    for (int i = 0; i < N; i++)
      ret[i] = this->coordTransfFunc(i)(x);
    return ret;
  }

  virtual VectorTo   getBasisVec(int ind, const VectorFrom& pos) { ... }
  virtual VectorFrom getInverseBasisVec(int ind, const VectorFrom& pos) { ... }

  MatrixNM<Real, N, N> jacobian(const VectorN<Real, N>& pos) { ... }

  VectorTo   transfVecContravariant(const VectorFrom& vec, const VectorFrom& pos) { ... }
  VectorFrom transfInverseVecCovariant(const VectorTo& vec, const VectorFrom& pos) { ... }
};
```

```
template<typename VectorFrom, typename VectorTo, int N>
class CoordTransfWithInverse : public virtual CoordTransf<VectorFrom, VectorTo, N>,
                               public virtual ICoordTransfWithInverse<VectorFrom, VectorTo, N>
{
public:
  virtual VectorFrom getContravarBasisVec(int ind, const VectorTo& pos) { ... }
  virtual VectorTo   getInverseContravarBasisVec(int ind, const VectorTo& pos) { ... }

  VectorTo   transfVecCovariant(const VectorFrom& vec, const VectorTo& pos) { ... }
  VectorFrom transfInverseVecContravariant(const VectorTo& vec, const VectorTo& pos) { ... }

  Tensor2<N> transfTensor2(const Tensor2<N>& tensor, const VectorFrom& pos) { ... }
  Tensor3<N> transfTensor3(const Tensor3<N>& tensor, const VectorFrom& pos) { ... }
  Tensor4<N> transfTensor4(const Tensor4<N>& tensor, const VectorFrom& pos) { ... }
  Tensor5<N> transfTensor5(const Tensor5<N>& tensor, const VectorFrom& pos) { ... }
};
```

Finally, example implementation for concrete spherical to cartesian transformation.

```
class CoordTransfSphericalToCartesian : public CoordTransfWithInverse<Vector3Spherical, Vector3Cartesian, 3>
{
private:
  // q[0] = r     - radial distance
  // q[1] = theta - inclination
  // q[2] = phi   - azimuthal angle
  static Real x(const VectorN<Real, 3>& q) { return q[0] * sin(q[1]) * cos(q[2]); }
  static Real y(const VectorN<Real, 3>& q) { return q[0] * sin(q[1]) * sin(q[2]); }
  static Real z(const VectorN<Real, 3>& q) { return q[0] * cos(q[1]); }

  // ...
  static Real r(const VectorN<Real, 3>& q)     { return sqrt(q[0]*q[0] + q[1]*q[1] + q[2]*q[2]); }
  static Real theta(const VectorN<Real, 3>& q) { return acos(q[2] / sqrt(q[0]*q[0] + q[1]*q[1] + q[2]*q[2])); }
  static Real phi(const VectorN<Real, 3>& q)   { return atan2(q[1], q[0]); }

  inline static ScalarFunction<3> _func[3] = { ScalarFunction<3>{x},
                                               ScalarFunction<3>{y},
                                               ScalarFunction<3>{z}
  };

  inline static ScalarFunction<3> _funcInverse[3] = { ScalarFunction<3>{r},
                                                      ScalarFunction<3>{theta},
                                                      ScalarFunction<3>{phi}
  };
public:
  Vector3Cartesian     transf(const Vector3Spherical& q)        const { return Vector3Cartesian{ x(q), y(q), z(q) }; }
  Vector3Spherical     transfInverse(const Vector3Cartesian& q) const { return Vector3Spherical{ r(q), theta(q), phi(q) }; }

  const IScalarFunction<3>& coordTransfFunc(int i)        const { return _func[i]; }
  const IScalarFunction<3>& inverseCoordTransfFunc(int i) const { return _funcInverse[i]; }
```

Example of a RotationXAxis transformation, that unlike spherical transformation, depends on a parameter (angle of rotation).

```
class CoordTransfCart3DRotationXAxis :
  public CoordTransfWithInverse<Vector3Cartesian, Vector3Cartesian, 3>
{
private:
  Real    _angle;
  MatrixNM<Real, 3, 3>  _transf;
  MatrixNM<Real, 3, 3>  _inverse;

  const ScalarFunctionFromStdFunc<3> _f1, _f2, _f3;
  const ScalarFunctionFromStdFunc<3> _fInverse1, _fInverse2, _fInverse3;
```

Fun begins with the constructor:

```
CoordTransfCart3DRotationXAxis(Real inAngle) : _angle(inAngle),
  _f1(std::function<Real(const VectorN<Real, 3>&)>
        { std::bind(&CoordTransfCart3DRotationXAxis::func1, this, std::placeholders::_1) }
    ),
  _f2(std::function<Real(const VectorN<Real, 3>&)>
        { std::bind(&CoordTransfCart3DRotationXAxis::func2, this, std::placeholders::_1) }
    ),
  _f3(std::function<Real(const VectorN<Real, 3>&)>
        { std::bind(&CoordTransfCart3DRotationXAxis::func3, this, std::placeholders::_1) }
    ),
  _fInverse1(std::function<Real(const VectorN<Real, 3>&)>
        { std::bind(&CoordTransfCart3DRotationXAxis::funcInverse1, this, std::placeholders::_1) }
    ),
  _fInverse2(std::function<Real(const VectorN<Real, 3>&)>
        { std::bind(&CoordTransfCart3DRotationXAxis::funcInverse2, this, std::placeholders::_1) }
    ),
  _fInverse3(std::function<Real(const VectorN<Real, 3>&)>
        { std::bind(&CoordTransfCart3DRotationXAxis::funcInverse3, this, std::placeholders::_1) }
    )
{
  _transf[0][0] = 1.0;
  _transf[1][1] = cos(_angle);
  _transf[1][2] = -sin(_angle);
  _transf[2][1] = sin(_angle);
  _transf[2][2] = cos(_angle);

  _inverse[0][0] = 1.0;
  _inverse[1][1] = cos(_angle);
  _inverse[1][2] = sin(_angle);
  _inverse[2][1] = -sin(_angle);
  _inverse[2][2] = cos(_angle);
}
```

11. All is not well, if you are in a non-inertial frame!

Wouldn't you know, there are some "fictious" forces in classical mechanics?

Tasks at hand:

- Investigating centrifugal force on a simple 2D carousel

PHYSICS

SIMPLE CAROUSEL AND CENTRIFUGAL FORCE

Carousel with radius of 20 meters, throwing darts

3 pikada, ako baci točno u centar (u njeovom coord sustavu), gdje će strelica završiti

INTRODUCING REFERENTIALFRAME

Carousel on carousel ☺

Shooting method za ODE's?

12. Projectile launch

Launching projectiles … what could be more fun.

Tasks at hand:

- A projectile is fired from the center of Ban Jelačić Square in Zagreb (45°48'47.4"N 15°58'38.3"E) at an angle of 45 degrees, in eastward direction. Ignoring air resistance, what is position of the projectile after one hour, for following values of the initial velocity (in m/s): 200, 1.000, 10.000, 15.000?
- What if we include air resistance?
- How can we simulate rocket motors (ie. the "projectile" doesn't get all its speed at the start)

ARTILLERY GRENADE – 200 M/S

Coriolis force enters the scene!

BALLISTIC ROCKET – 1000 M/S

LOW ORBIT SATELLITE – 10000 M/S

HITTING THE MOON AND BEYOND – 15000 M/S

We will revisit this problem for special relativity velocities

13. Rigid body

Point-like mechanical particles are great … but there is more to mechanics than that.

Task at hand:

- Todo! Običan kvadar, bez gravitacije, gurneš ga nekom silom I što se događa
- Spinning top without gravity
- Tensors
- Eigenvalues

introducing tensors and their transformations

PHYSICS OF RIGID BODY

Moment of inertia

Eigenvalues

Euler equations

TENSORS

Basic interface for rank 2 tensor (similar defined up to rank 5).

```
template<int N>
class ITensor2
{
public:
  virtual int   NumContravar() const = 0;
  virtual int   NumCovar() const = 0;

  virtual Real  operator()(int i, int j) const = 0;
  virtual Real& operator()(int i, int j) = 0;
};
```

Concrete implementation

```
template <int N>
class Tensor2 : public ITensor2<N>
{
  MatrixNM<Real, N, N> _coeff;
public:
  int _numContravar = 0;
  int _numCovar = 0;
  bool _isContravar[2];

  Tensor2(int nCovar, int nContraVar) { ... }
  Tensor2(int nCovar, int nContraVar, std::initializer_list<Real> values) { ... }

  int  NumContravar() const { return _numContravar; }
  int  NumCovar()     const { return _numCovar; }

  bool IsContravar(int i) const { return _isContravar[i]; }
  bool IsCovar(int i) const     { return !_isContravar[i]; }

  Real  operator()(int i, int j) const override { return _coeff[i][j]; }
  Real& operator()(int i, int j) override       { return _coeff[i][j]; }

  Tensor2 operator+(const Tensor2& other) const { ... }
  Tensor2 operator-(const Tensor2& other) const { ... }
  Tensor2 operator*=(Real scalar) const { ... }
  Tensor2 operator/(Real scalar) const { ... }

  friend Tensor2 operator*(Real scalar, const Tensor2& b) { ... }

  Real Contract() const { ... }
  Real operator()(const VectorN<Real, N>& v1, const VectorN<Real, N>& v2) const { ... }

  void   Print(std::ostream& stream, int width, int precision) const { ... }
  friend std::ostream& operator<<(std::ostream& stream, const Tensor2& a) { ... }
};
```

TENSOR TRANSFORMATIONS

Transformation of rank 2 tensor.

Member of CoordTransfWithInverse abstract class, and available for every inherited coordinate transformation class.

```
Tensor2<N> transfTensor2(const Tensor2<N>& tensor, const VectorFrom& pos)
{
  Tensor2<N> ret(tensor.NumContravar(), tensor.NumCovar());

  for (int i = 0; i < N; i++)
    for (int j = 0; j < N; j++)
    {
      ret(i, j) = 0;
      for (int k = 0; k < N; k++)
        for (int l = 0; l < N; l++)
        {
          double coef1, coef2;
          if (tensor._isContravar[0])
            coef1 = Derivation::NDer1Partial(this->coordTransfFunc(i), k, pos);
          else
            coef1 = Derivation::NDer1Partial(this->inverseCoordTransfFunc(k), i, pos);

          if (tensor._isContravar[1])
            coef2 = Derivation::NDer1Partial(this->coordTransfFunc(j), l, pos);
          else
            coef2 = Derivation::NDer1Partial(this->inverseCoordTransfFunc(l), j, pos);

          ret(i, j) += coef1 * coef2 * tensor(k, l);
        }
    }

  return ret;
}
```

CALCULATING MOMENT OF INERTIA

Calculating moment of inertia for a set of discrete masses

Necessary models:

```
struct DiscreteMass {
    Vector3Cartesian _position;
    double _mass;

    DiscreteMass(const Vector3Cartesian &position, const double& mass)
        : _position(position), _mass(mass)  { }
};
struct DiscreteMassesConfig {
    std::vector<DiscreteMass> _masses;

    DiscreteMassesConfig(const std::vector<DiscreteMass>& masses)
        : _masses(masses)  { }
};
```

Calculator

```
class DiscreteMassMomentOfInertiaTensorCalculator
{
    DiscreteMassesConfig _massesConfig;
public:
    DiscreteMassMomentOfInertiaTensorCalculator(const DiscreteMassesConfig& massesConfig)
        : _massesConfig(massesConfig) { }

    Tensor2<3> calculate()
    {
        Tensor2<3> tensor(2,0);  // can be (0,2) or (1,1) as well (it is a Cartesian tensor)
        for (const auto& mass : _massesConfig._masses)
        {
            Vector3Cartesian pos = mass._position;
            tensor(0,0) += mass._mass * (pos.Y() * pos.Y() + pos.Z() * pos.Z());
            tensor(1,1) += mass._mass * (pos.X() * pos.X() + pos.Z() * pos.Z());
            tensor(2,2) += mass._mass * (pos.X() * pos.X() + pos.Y() * pos.Y());

            tensor(0,1) -= mass._mass * pos.X() * pos.Y();
            tensor(0,2) -= mass._mass * pos.X() * pos.Z();
            tensor(1,2) -= mass._mass * pos.Y() * pos.Z();

            tensor(1,0) = tensor(0,1);
            tensor(2,0) = tensor(0,2);
            tensor(2,1) = tensor(1,2);
        }
        return tensor;
    }
};
```

Calculating moment of inertia for continuous mass

CALCULATING EIGENVALUES

SIMULATING RIGID BODY

14. Rotations and quaternions

Orientation, orientation, orientation … and transformation.

Tasks at hand:

- Rotations
- Quaternions

REPRESENTING ROTATIONS

QUATERNIONS

15. Motion in spacetime – Lorentz transformations

When your speed approaches speed of light, strange things tend to happen.

Tasks at hand:

- Basics of special relativity and Lorentz transformations
- Introduce Vector4Lorentz and LorentzTransformation classes

PHYSICS – BASICS OF SPECIAL RELATIVITY

VECTOR4LORENTZ

Adding time as coordinate for specifying vectors in four-dimensional spacetime.

Per almost universal custom, time coordinate is first one, with convenient index 0.

```
class Vector4Lorentz : public VectorN<Real, 4>
{
public:
  Real  T() const { return _val[0]; }
  Real& T()       { return _val[0]; }
  Real  X() const { return _val[1]; }
  Real& X()       { return _val[1]; }
  Real  Y() const { return _val[2]; }
  Real& Y()       { return _val[2]; }
  Real  Z() const { return _val[3]; }
  Real& Z()       { return _val[3]; }

  Vector4Lorentz() : VectorN<Real, 4>{ 0.0, 0.0, 0.0, 0.0 } {}
  Vector4Lorentz(std::initializer_list<Real> list) : VectorN<Real, 4>(list) { }
};
```

LORENTZTRANSFORMATION

TODO – general Lorentz transformation, for a boost in any direction

METRIC TENSOR

Interface for rank two tensor field in N dimensions.

```
template<int N>
class ITensorField2 : public IFunction<Tensor2<N>, const VectorN<Real, N>& >
{
  int _numContravar;
  int _numCovar;
public:
  ITensorField2(int numContra, int numCo) : _numContravar(numContra), _numCovar(numCo) { }

  int getNumContravar() const { return _numContravar; }
  int getNumCovar()     const { return _numCovar; }

  // concrete implementations need to provide this
  virtual Real Component(int i, int j, const VectorN<Real, N>& pos) const = 0;

  virtual ~ITensorField2() {}
};
```

Abstract class representing general metric tensor field, defined throughout the whole space.

```
template<int N>
class MetricTensorField : public ITensorField2<N>
{
public:
  MetricTensorField() : ITensorField2<N>(2, 0) { }
  MetricTensorField(int numContra, int numCo) : ITensorField2<N>(numContra, numCo) { }

  // implementing operator() requried by IFunction interface
  Tensor2<N>   operator()(const VectorN<Real, N>& pos) const
  {
    Tensor2<N> ret(this->getNumContravar(), this->getNumCovar());

    for (int i = 0; i < N; i++)
      for (int j = 0; j < N; j++)
        ret(i, j) = this->Component(i, j, pos);

    return ret;
  }

  Real GetChristoffelSymbolFirstKind(int i, int j, int k, const VectorN<Real, N>& pos) const
  Real GetChristoffelSymbolSecondKind(int i, int j, int k, const VectorN<Real, N>& pos) const

  VectorN<Real, N> CovariantDerivativeContravar(const IVectorFunction<N>& func, int j,
                                                const VectorN<Real, N>& pos) const { ... }
  Real CovariantDerivativeContravarComp(const IVectorFunction<N>& func, int i, int j,
                                        const VectorN<Real, N>& pos) const { ... }

  VectorN<Real, N> CovariantDerivativeCovar(const IVectorFunction<N>& func, int j,
                                            const VectorN<Real, N>& pos) const { ... }
  Real CovariantDerivativeCovarComp(const IVectorFunction<N>& func, int i, int j,
                                    const VectorN<Real, N>& pos) const { ... }
};
```

Simplest example is metric tensor for Cartesian space in three dimensions.

```
class MetricTensorCartesian3D : public MetricTensorField<3>
{
public:
  MetricTensorCartesian3D() : MetricTensorField<3>(2, 0) { }

  Real Component(int i, int j, const VectorN<Real, 3>& pos) const
  {
    if (i == j)
      return 1.0;
    else
      return 0.0;
  }
};
```

Metric tensor for spherical coordinates comes in two variants.

Covariant

```
class MetricTensorSpherical : public MetricTensorField<3>
{
public:
  MetricTensorSpherical() : MetricTensorField<3>(0, 2) { }

  virtual  Real Component(int i, int j, const VectorN<Real, 3>& pos) const override
  {
    if (i == 0 && j == 0)
      return 1.0;
    else if (i == 1 && j == 1)
      return POW2(pos[0]);
    else if (i == 2 && j == 2)
      return pos[0] * pos[0] * sin(pos[1]) * sin(pos[1]);
    else
      return 0.0;
  }
};
```

And contravariant (which is just the inverse of covariant version).

```
class MetricTensorSphericalContravar : public MetricTensorField<3>
{
public:
  MetricTensorSphericalContravar() : MetricTensorField<3>(2, 0) { }

  virtual Real Component(int i, int j, const VectorN<Real, 3>& pos) const
  {
    if (i == 0 && j == 0)
      return 1.0;
    else if (i == 1 && j == 1)
      return 1 / (pos[0] * pos[0]);
    else if (i == 2 && j == 2)
      return 1 / (pos[0] * pos[0] * sin(pos[1]) * sin(pos[1]));
    else
      return 0.0;
  }
};
```

Finally, we come to metric tensor for spacetime, which we will call MetricTensorMinkowski:

```
class MetricTensorMinkowski : public MetricTensorField<4>
{
public:
  MetricTensorMinkowski() : MetricTensorField<4>(2, 0) {}

  virtual Real Component(int i, int j, const VectorN<Real, 4>& pos) const override
  {
    if (i == 0 && j == 0)
      return -1.0;
    else if (i == 1 && j == 1)
      return 1.0;
    else if (i == 2 && j == 2)
      return 1.0;
    else if (i == 3 && j == 3)
      return 1.0;
    else
      return 0.0;
  }
};
```

SOLVED EXAMPLES

Projectile launch with relativistic speed

Continuing our example from Chapter 12, what is position if we launch it with speeds: 0.1c, 0.3c, 0.5c, 0.8c, 0.9c, 0.95c?

Earth gravity and Coriolis force are not relevant here, and the only important

Passenger on train dropping ball

Moving on a train with 0.8c, passenger drops a ball to the floor. At what time it hits the floor for passenger, and stationary observer

Spherical ball passing observer with relativistic speed

Spherical ball, 1 meter in diameter, is travelling with speed 0.9c along a line that at its closest is 100 meters from observer.

Observer has an extremely fast camera with a tracker that ensures camera is pointed exactly at the centre of the sphere at all times.

16. Special relativity – resolving twin-paradox

Where we investigate the most famous "paradox" of them all.

Task at hand:

- Simulate numerically twin paradox
- Simple case with linear trajectory from A to B
- Realistic case with acceleration and a real trajectory to destination

PHYSICS OF PROPER TIME

NUMERICAL SIMULATION

17. Static electric fields

Starting our investigations in electromagnetism.

Task at hand:

- Calculate electric fields for different charge configurations.
- Verify Gauss and Stokes law, both in integral and differential form.

PHYSICS – COULOMB LAW

Jednostavno numeričko izračunavanje potencijala za analitički poznata rješenja I usporedba

SIMULATING DISTRIBUTION OF CHARGE ON A SOLID BODY

What is distribution of charge

Sfera

Cilindar

Kvadar

Something with “pointy”

ELECTRIC FIELD OF A ROD WITH FINITE LENGTH

In previous section we calculated distribution of charge

Which means we can now calculate electric field throughout space

But actually, we want field lines visualized

Projection in plane

POTENTIAL AND WORK IN ELECTRIC FIELD

CONDUCERS AND DIELECTRICS

18. Static magnetic fields

Looking at static magnetic fields.

Task at hand:

- Calculate magnetic fields for different current configurations.

PHYSICS - BIOT-SAVART LAW

Magnetic field of a simple loop with passing current

19. Dynamic EM fields

What happens when charges and currents are not static?

Task at hand:

- Investigate dynamic electromagnetic fields.
- Introduce electro-magnetic tensor
- EM field of a moving charge

PHYSICS – MAXWELL'S EQUATIONS

INTRODUCING EM TENSOR

```
Tensor2<4> GetEMTensorContravariant(Vector3Cartesian E_field, Vector3Cartesian B_field)
{
  double c = 1.0;

  Tensor2<4> EM_tensor(2, 0);

  EM_tensor(0, 0) = 0.0;
  EM_tensor(0, 1) = -E_field.X() / c;
  EM_tensor(0, 2) = -E_field.Y() / c;
  EM_tensor(0, 3) = -E_field.Z() / c;

  EM_tensor(1, 0) = E_field.X() / c;
  EM_tensor(1, 1) = 0.0;
  EM_tensor(1, 2) = -B_field.Z();
  EM_tensor(1, 3) = B_field.Y();

  EM_tensor(2, 0) = E_field.Y() / c;
  EM_tensor(2, 1) = B_field.Z();
  EM_tensor(2, 2) = 0.0;
  EM_tensor(2, 3) = -B_field.X();

  EM_tensor(3, 0) = E_field.Z() / c;
  EM_tensor(3, 1) = -B_field.Y();
  EM_tensor(3, 2) = B_field.X();
  EM_tensor(3, 3) = 0.0;

  return EM_tensor;
}
```

LIENARD-WIECHERT POTENTIAL OF MOVING CHARGE

Basic calculation

```
// Given t and r in lab frame of the observer, calculate Lienard-Wiechert potentials
// for charge moving along x-axis with given velocity
Real calcLienardWiechertScalarPotential(Vector3Cartesian r_at_point, Real t, Vector3Cartesian rs_charge_pos,
                                        Real q, Real charge_velocity)
{
  double c = 3e8;
  Vec3Cart charge_v(charge_velocity, 0, 0);

  // calculate retarded time
  Real r = (r_at_point - rs_charge_pos).NormL2();
  Real tr = t - (r_at_point - rs_charge_pos).NormL2() / c;

  // calculate retarded position
  Vec3Cart r_ret_charge_pos = r_at_point - charge_v * (t - tr);

  Real beta = charge_v.NormL2() / c;
  Vec3Cart ns = (r_at_point - r_ret_charge_pos) / (r_at_point - r_ret_charge_pos).NormL2();

  Real scalar_potential = q / ((r_at_point - r_ret_charge_pos).NormL2() * (1 - beta * ScalarProduct(ns, charge_v) / c));

  return scalar_potential;
}
```

TODO;

Parametrizacija moving naboja, što mu je t?

Imamo grid postavljenih mjeritelja el. Polja, koje s brzinom c vraćaju signale nazad do observera

Ispaljuje se naboj brzinom 0.8 c u t = 0, za observera

Simulacija takva da je u prvih 10 dT, kod observera polja nema, a na 10d dT dođe prvi signal od najbližžeg mjeritelja točki ispaljivanja

SIMPLE ANTENNA?

Varying current through antenna and resulting electric field

20. Differential geometry of curves and surfaces

Diving into some differential geometry with curves and surfaces.

Task at hand:

- Implement numerical calculations of curves and surfaces differential geometry properties.
- Frenet-Serret formulas, moving trihedron
- Connection with velocity and acceleration

CURVES

SURFACES

LOOKING TO MANIFOLDS

Sphere as a manifold

Can we calculate some geodesics?

21. General relativity

Going to the final frontier.

Task at hand:

- Schwarzschild geometry of black hole. How does crossing the event horizon looks from perspective of observer and traveler.
- How it is different for Kerr metric

EINSTEIN'S EQUATION

STATIC BLACK HOLE - SCHWARZSCHILD'S METRIC

ROTATING BLACK HOLE - KERR METRIC