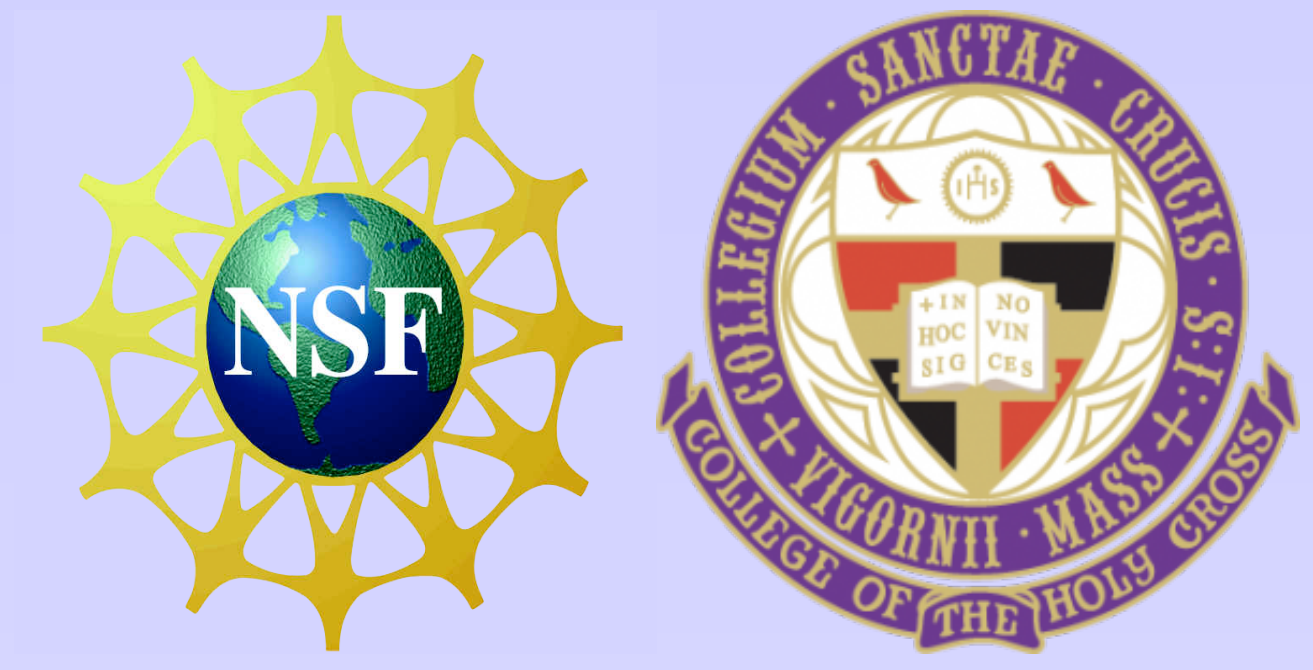


# Linearly Stable Relative Equilibria Utilizing a Dominant Mass

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## N-BODY PROBLEM

Given  $n$  bodies in space with initial positions and velocities, under mutual gravitational attraction, what is their future motion?

Define:

$$m_i = \text{mass of the } i\text{-th body} \quad \mathbf{q}_i = \text{position of the } i\text{-th body in } \mathbb{R}^2$$

$F = ma$  gives,

$$m_i \ddot{\mathbf{q}}_i = \sum_{j \neq i}^n \frac{m_i m_j (\mathbf{q}_j - \mathbf{q}_i)}{\|\mathbf{q}_i - \mathbf{q}_j\|^3} \quad \text{for each } i \in (1, 2, \dots, n)$$

## CENTRAL CONFIGURATIONS

A **central configuration** (c.c.) is an initial configuration of bodies  $\mathbf{x}_i$ , which satisfies the following equation

$$\sum_{j \neq i}^n \frac{m_i m_j (\mathbf{x}_j - \mathbf{x}_i)}{\|\mathbf{x}_j - \mathbf{x}_i\|^3} + \omega^2 m_i \mathbf{x}_i = 0 \quad \forall i \in (1 \dots n)$$

for some proportionality constant  $\omega^2$ .

- Providing a c.c. with the correct choice of initial velocities leads to a periodic solution called a **relative equilibrium**.
- Released from rest, a c.c. maintains the same shape as it heads toward total collision.
- Any Kepler orbit can be attached to a c.c. to obtain a new solution to the  $n$ -body problem.
- **Key Fact:** Central configurations are critical points of the Newtonian potential function  $U$  restricted to the level surface  $I = I_0$ .

$$\text{where } I = \frac{1}{2} \sum_{i=1}^n m_i \|\mathbf{x}_i\|^2$$

## LINEAR STABILITY

Due to symmetry, there are two invariant subspaces  $W_1$  and  $W_2$  that lead to the eight eigenvalues  $0, 0, \pm\omega i, \pm\omega i, \pm\omega i, \pm\omega i$ , for any relative equilibrium  $x$ . We say  $\mathbf{x}$  is **nondegenerate** if the remaining  $4n - 8$  eigenvalues are nonzero. It is **spectrally stable** if the eigenvalues are pure imaginary and is **linearly stable** if in addition, the restriction of the matrix obtained upon linearizing about  $x$ , to the skew-orthogonal complement of  $W_1 \cup W_2$  is diagonalizable.

## KNOWN RESULTS

- In 1772, Lagrange discovered that three bodies of any mass located at the vertices of an equilateral triangle represent a solution to the 3-body problem. In 1843 Gascheau (and later in 1875 Routh) determined stability for Lagrange's solution iff

$$\frac{m_1 m_2 + m_1 m_3 + m_2 m_3}{(m_1 + m_2 + m_3)^2} < \frac{1}{27}$$

- All collinear relative equilibria are unstable

## GOAL

We want to determine if linearly stability in a relative equilibrium implies the existence of a dominant mass in the configuration. In other words, given a linearly stable relative equilibrium, we want to find the smallest possible ratio between the dominant mass and the sum of the remaining masses, for various  $n$  values. (*Rick Moeckel*)

- We normalize the sum of the non-dominant masses to 1:  $\sum_{i=2}^{n+1} m_i = 1$ .
- Let  $R = \frac{m_1}{m_2 + m_3 + \dots + m_{n+1}}$ , and assume  $m_1 > m_2 > \dots > m_{n+1}$

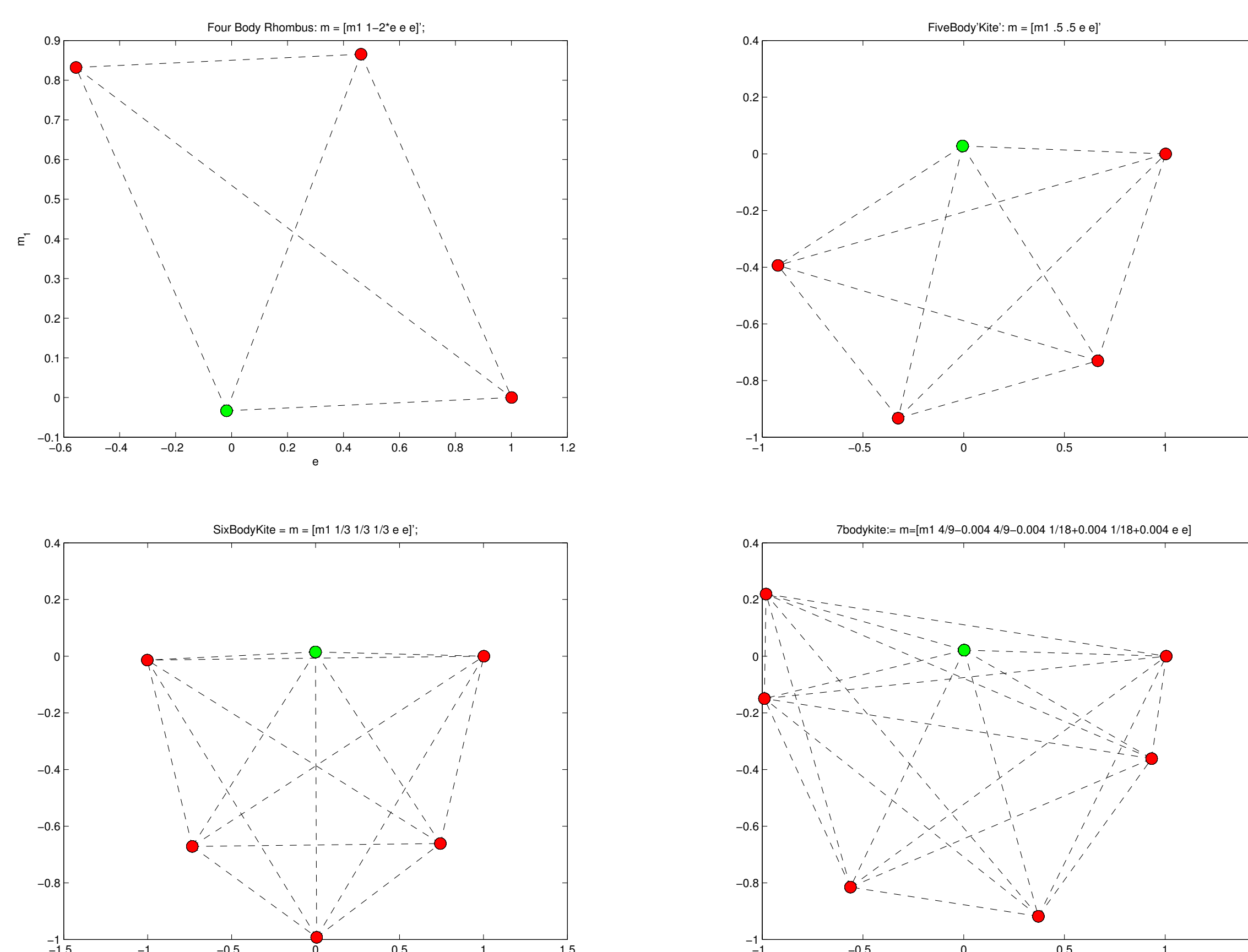
We want to find the infimum of  $R$  for different  $n$  values in the  $(1+n)$ -body problem

## RESULTS

$n$	$R$
2	24.9599
3	24.9599
4	25.5132
5	31.5595
6	36.9582
7	19.9789
8	26.5326
9	33.7930
10	42.0993

*Note:* For  $n = 3$  and  $n = 4$  the analytic results are,  $m_1 = \frac{25+3\sqrt{69}}{2} \approx 24.9599$

**Conjecture:** We want the limiting configuration to have bodies that don't collide, and we expect symmetry to lead to the best result



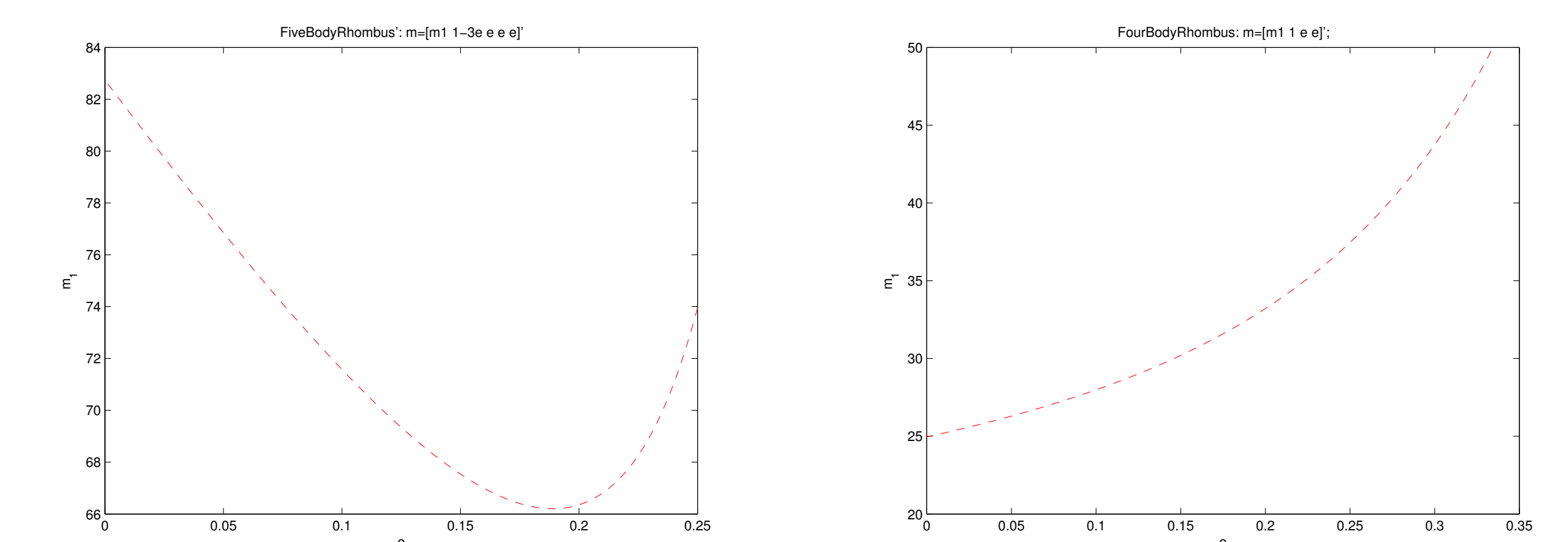
## ACKNOWLEDGMENTS

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## TECHNIQUES: MATLAB

- We use gradient flow to locate minima of the Newtonian potential function  $U$  constrained to a level surface of the moment of inertia  $I = \frac{1}{2}$ .
- Given an initial configuration  $\mathbf{x}_0$  and a set of masses  $m$ , a MatLab function called `config_analyzer(x0, m)` was written to find a local minimum and determine its stability.
- Numerics: ODE15s (stiff ODE), `RelTol`, `AbsTol` = 1e-10, and  $\|M^{-1} \nabla U(\mathbf{x}) + \omega^2 \mathbf{x}\|$  is always  $\leq 1e-13$ . Check if real parts of eigenvalues are 0 (within 1e-10).
- For each family of relative equilibria, we use a "binary search" method incorporating `config_analyzer()` to locate the smallest possible  $m_1$  such that the corresponding relative equilibrium is linearly stable.

## CLUSTERING



Clustering example

Non-clustering example

**Conjecture:** Let  $m_i, m_j = \epsilon$ . If  $\lim_{\epsilon \rightarrow 0} r_{ij} = 0$ , then the dominant mass required to keep the relative equilibrium linearly stable increases as  $\epsilon \rightarrow 0$ .

## 1 + n-GON

- For  $n \geq 7$  the  $(1+n)$ -gon is a linearly stable relative equilibrium iff the central mass is at least  $0.435n^3$  (Roberts 2000) (Moeckel 1994).

