



Conformal Lagrangian Dynamics on Contact 9- Manifolds

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ARTICLE INFO

Article history:

Received: 15 May 2017;

Received in revised form:

12 June 2017;

Accepted: 24 June 2017;

ABSTRACT

In this study, we concluded the Conformal Lagrangian Dynamics on (TM, ξ, J) , being a model. Finally introduce, some geometrical and physical results on the related mechanic systems have been discussed.

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Keywords

Differential geometry,
Contact 9- Manifolds,
Lagrangian Dynamics.

1. Introduction

Differential geometry is a rich and beautiful field in pure mathematics whose origins lie in classical physics. Specifically, Contact spaces arose as the natural setting in which to study Lagrangian mechanics. A Contact structure is precisely what is needed to associate a dynamical system on the space to each energy function.

It is the most important studies on the subject of paper is a study entitled (Lagrangian Mechanics on Contact 5- Manifolds)

In the study entitled conformal Euler-Lagrange mechanical on contact 5- Manifolds, presents Lagrangian Mechanics on contact 5- manifolds. In the end, the some results related to contact 5- manifolds. dynamical systems are also discussed

The paper is structured as follows. In second 2, we review contact 5- manifolds. In second 3 we introduce Lagrangian equations for dynamical systems on contact 5- manifold. In conclusion, we discuss some geometric-physical results about Lagrangian equations and fields constructed on the base manifolds

2. Contact 9- Manifolds

Definition 2-1 [2]

Let M be a manifold of odd dimension $(2n+1)$ and ξ field. The pair (M, ξ) is called a contact manifold

Theorem 2-2. A conformal manifold is a differentiable manifold equipped with an equivalence class of Riemann metric tensors, in which two f_1 metrics f_2 and are equivalent if and only if

$$f_2 = B^2 f_1 \quad (1)$$

where B is a smooth positive function. $B > 0$

Theorem 2.3

[1] A conformal transformation is a change of coordinates such that the metric changes by $\sigma^a \rightarrow \sigma^b$

$$f_{ab}(\sigma) \rightarrow B^2(\sigma) f_{ab}(\sigma) \quad (2)$$

Theorem 2.4

Let $\left(\frac{\partial}{\partial x_1}, \frac{\partial}{\partial x_2}, \frac{\partial}{\partial x_3}, \frac{\partial}{\partial x_4}, \frac{\partial}{\partial x_5}, \frac{\partial}{\partial x_6}, \frac{\partial}{\partial x_7}, \frac{\partial}{\partial x_8}\right)$ bases on manifold, J Conformal to the structure coefficient

$$\begin{aligned} J\left(\frac{\partial}{\partial x_1}\right) &= B^2 \cos \theta \left(\frac{\partial}{\partial x_5}\right) + B^2 \sin \theta \left(\frac{\partial}{\partial x_6}\right), & J\left(\frac{\partial}{\partial x_2}\right) &= B^2 \cos \theta \left(\frac{\partial}{\partial x_6}\right) + B^2 \sin \theta \left(\frac{\partial}{\partial x_5}\right) \\ J\left(\frac{\partial}{\partial x_3}\right) &= -B^2 \cos \theta \left(\frac{\partial}{\partial x_7}\right) + B^2 \sin \theta \left(\frac{\partial}{\partial x_8}\right), & J\left(\frac{\partial}{\partial x_4}\right) &= -B^2 \cos \theta \left(\frac{\partial}{\partial x_8}\right) + B^2 \sin \theta \left(\frac{\partial}{\partial x_7}\right) \\ J\left(\frac{\partial}{\partial x_5}\right) &= -B^{-2} \cos \theta \left(\frac{\partial}{\partial x_1}\right) - B^{-2} \sin \theta \left(\frac{\partial}{\partial x_2}\right), & J\left(\frac{\partial}{\partial x_6}\right) &= B^{-2} \cos \theta \left(\frac{\partial}{\partial x_2}\right) - B^{-2} \sin \theta \left(\frac{\partial}{\partial x_1}\right) \\ J\left(\frac{\partial}{\partial x_7}\right) &= -B^{-2} \cos \theta \left(\frac{\partial}{\partial x_3}\right) - B^{-2} \sin \theta \left(\frac{\partial}{\partial x_4}\right), & J\left(\frac{\partial}{\partial x_8}\right) &= B^{-2} \cos \theta \left(\frac{\partial}{\partial x_4}\right) - B^{-2} \sin \theta \left(\frac{\partial}{\partial x_3}\right) \end{aligned}$$

3. Lagrangian Dynamics

Definition 3.1 [1].

A Lagrangian function for a Hamiltonian vector field ξ on M is a smooth function $L : TM \rightarrow \mathbb{R}$ such that

$$i_{\xi} \omega_L = dE_L \quad (3)$$

Kinetic energy given $T : M \rightarrow \mathbb{R}$ such that

$$T = \frac{1}{2} m_i (\dot{x}_1^2 + \dot{x}_2^2 + \dot{x}_3^2 + \dot{x}_4^2 + \dot{x}_5^2 + \dot{x}_6^2 + \dot{x}_7^2 + \dot{x}_8^2) \quad (4)$$

Potential energy $P: M \rightarrow R$ such that

$$P = m_i g h \quad (5)$$

$m_i = \text{mass}$ and $h = \text{stand}$, $g = \text{gravity acceleration}$

The Lagrangian function $L: R^{10n} \rightarrow R$ is map that satisfies the condition then

$$L = T - P \quad (6)$$

Definition 3.2 [2].

A Lagrangian system is a triple $(M; \xi)$, where $(\omega; L)$ is a Symplectic manifold and $L \in C^\infty(M)$ is a function, called the Hamiltonian function.

Theorem 3.3

Let M be m -real dimensional configuration manifold. A tensor field J on TM is called an almost complex structure on TM if at every point p of TM , J is endomorphism of the tangent space $T_p(M)$ such that $J^2 = -1$ are complex is

$$J^2 \left(\frac{\partial}{\partial x_i} \right) = - \frac{\partial}{\partial x_i} \quad i = 1, 2, 3, 4, 5, 6, 7, 8 \quad (7)$$

J is called almost complex manifold

Proposition 3.4

Let λ be the vector field characterized by

$$\lambda = \sum_{i=1}^8 \left(X^i \frac{\partial}{\partial x_i} \right) \quad X^i = \dot{x}^i \quad (8)$$

(TM, g, J) . then vector field defined by

$$J(\lambda) = J \left(\sum_{i=1}^8 \left(X^i \frac{\partial}{\partial x_i} \right) \right) = \sum_{i=1}^8 X^i J \left(\frac{\partial}{\partial x_i} \right)$$

$$J(\lambda) = X^1 J \left(\frac{\partial}{\partial x_1} \right) + X^2 J \left(\frac{\partial}{\partial x_2} \right) + X^3 J \left(\frac{\partial}{\partial x_3} \right) + X^4 J \left(\frac{\partial}{\partial x_4} \right) + X^5 J \left(\frac{\partial}{\partial x_5} \right) + X^6 J \left(\frac{\partial}{\partial x_6} \right) + X^7 J \left(\frac{\partial}{\partial x_7} \right) + X^8 J \left(\frac{\partial}{\partial x_8} \right)$$

$$J(\lambda) =$$

$$X^1 J \left(B^2 \cos \theta \left(\frac{\partial}{\partial x_5} \right) + B^2 \sin \theta \left(\frac{\partial}{\partial x_6} \right) \right) + X^2 J \left(B^2 \cos \theta \left(\frac{\partial}{\partial x_6} \right) + B^2 \sin \theta \left(\frac{\partial}{\partial x_5} \right) \right) + X^3 J \left(-B^2 \cos \theta \left(\frac{\partial}{\partial x_7} \right) + B^2 \sin \theta \left(\frac{\partial}{\partial x_8} \right) \right) +$$

$$X^4 J \left(-B^2 \cos \theta \left(\frac{\partial}{\partial x_8} \right) + B^2 \sin \theta \left(\frac{\partial}{\partial x_7} \right) \right) + X^5 J \left(-B^2 \cos \theta \left(\frac{\partial}{\partial x_1} \right) - B^2 \sin \theta \left(\frac{\partial}{\partial x_2} \right) \right) +$$

$$X^6 J \left(B^2 \cos \theta \left(\frac{\partial}{\partial x_2} \right) - B^2 \sin \theta \left(\frac{\partial}{\partial x_1} \right) \right) + X^7 J \left(-B^2 \cos \theta \left(\frac{\partial}{\partial x_3} \right) - B^2 \sin \theta \left(\frac{\partial}{\partial x_4} \right) \right) +$$

$$X^8 J \left(B^2 \cos \theta \left(\frac{\partial}{\partial x_4} \right) - B^2 \sin \theta \left(\frac{\partial}{\partial x_3} \right) \right)$$

Liouville vector field on contact 9-manifold (TM, g, J) . then vector field defined by energy function given by

$$E_L^{G_1} = U_{G_1}(L) - L$$

is vertical derivation (differentiation) d_{G_1}

is defined

$$d_{G_1} = [i_{G_1}, d] = i_{G_1} d - d i_1$$

$$d = \sum_{i=1}^8 \left(\frac{\partial}{\partial x_i} dx_i \right) = \frac{\partial}{\partial x_1} dx_1 + \frac{\partial}{\partial x_2} dx_2 + \frac{\partial}{\partial x_3} dx_3 + \frac{\partial}{\partial x_4} dx_4 + \frac{\partial}{\partial x_5} dx_5 + \frac{\partial}{\partial x_6} dx_6 + \frac{\partial}{\partial x_7} dx_7 + \frac{\partial}{\partial x_8} dx_8$$

The $d_J: F(M) \rightarrow \wedge^1 M$

$$d_J = J(d) = \sum_{i=1}^8 J \left(\frac{\partial}{\partial x_i} \right) dx_i$$

$$= J \left(\frac{\partial}{\partial x_1} \right) dx_1 + J \left(\frac{\partial}{\partial x_2} \right) dx_2 + J \left(\frac{\partial}{\partial x_3} \right) dx_3 + J \left(\frac{\partial}{\partial x_4} \right) dx_4 + J \left(\frac{\partial}{\partial x_5} \right) dx_5 + J \left(\frac{\partial}{\partial x_6} \right) dx_6 + J \left(\frac{\partial}{\partial x_7} \right) dx_7$$

$$+ J \left(\frac{\partial}{\partial x_8} \right) dx_8$$

$$d_J L =$$

$$\left(B^2 \cos \theta \left(\frac{\partial L}{\partial x_5} \right) + B^2 \sin \theta \left(\frac{\partial L}{\partial x_6} \right) \right) dx_1 + \left(B^2 \cos \theta \left(\frac{\partial L}{\partial x_6} \right) + B^2 \sin \theta \left(\frac{\partial L}{\partial x_5} \right) \right) dx_2 + \left(-B^2 \cos \theta \left(\frac{\partial L}{\partial x_7} \right) + B^2 \sin \theta \left(\frac{\partial L}{\partial x_8} \right) \right) dx_3 +$$

$$\left(-B^2 \cos \theta \left(\frac{\partial L}{\partial x_8} \right) + B^2 \sin \theta \left(\frac{\partial L}{\partial x_7} \right) \right) dx_4 + \left(-B^2 \cos \theta \left(\frac{\partial L}{\partial x_1} \right) - B^2 \sin \theta \left(\frac{\partial L}{\partial x_2} \right) \right) dx_5 +$$

$$\left(B^2 \cos \theta \left(\frac{\partial L}{\partial x_2} \right) - B^2 \sin \theta \left(\frac{\partial L}{\partial x_1} \right) \right) dx_6 + \left(-B^2 \cos \theta \left(\frac{\partial L}{\partial x_3} \right) - B^2 \sin \theta \left(\frac{\partial L}{\partial x_4} \right) \right) dx_7 +$$

$$\left(B^2 \cos \theta \left(\frac{\partial L}{\partial x_4} \right) - B^2 \sin \theta \left(\frac{\partial L}{\partial x_3} \right) \right) dx_8$$

$$\text{Let } \phi_L = -d(Jd) = -d(d_J L) = -d \left(\left(B^2 \cos \theta \left(\frac{\partial L}{\partial x_5} \right) + B^2 \sin \theta \left(\frac{\partial L}{\partial x_6} \right) \right) dx_1 + \left(B^2 \cos \theta \left(\frac{\partial L}{\partial x_6} \right) + B^2 \sin \theta \left(\frac{\partial L}{\partial x_5} \right) \right) dx_2 + \right.$$

$$\left. \left(-B^2 \cos \theta \left(\frac{\partial L}{\partial x_7} \right) + B^2 \sin \theta \left(\frac{\partial L}{\partial x_8} \right) \right) dx_3 + \left(-B^2 \cos \theta \left(\frac{\partial L}{\partial x_8} \right) + B^2 \sin \theta \left(\frac{\partial L}{\partial x_7} \right) \right) dx_4 + \right.$$

$$\left(-B^{-2}\cos\theta\left(\frac{\partial L}{\partial x_1}\right)-B^{-2}\sin\theta\left(\frac{\partial L}{\partial x_2}\right)\right)dx_5+\left(B^{-2}\cos\theta\left(\frac{\partial L}{\partial x_2}\right)-B^{-2}\sin\theta\left(\frac{\partial L}{\partial x_1}\right)\right)dx_6+\\ \left(-B^{-2}\cos\theta\left(\frac{\partial L}{\partial x_3}\right)-B^{-2}\sin\theta\left(\frac{\partial L}{\partial x_4}\right)\right)dx_7+\left(B^{-2}\cos\theta\left(\frac{\partial L}{\partial x_4}\right)-B^{-2}\sin\theta\left(\frac{\partial L}{\partial x_3}\right)\right)dx_8$$

$$d=\sum_{i=1}^8\left(\frac{\partial}{\partial x_i}dx_i\right)=\frac{\partial}{\partial x_1}dx_1+\frac{\partial}{\partial x_2}dx_2+\frac{\partial}{\partial x_3}dx_3+\frac{\partial}{\partial x_4}dx_4+\frac{\partial}{\partial x_5}dx_5+\frac{\partial}{\partial x_6}dx_6+\frac{\partial}{\partial x_7}dx_7+\frac{\partial}{\partial x_8}dx_8$$

The $d_J:F(M)\rightarrow\wedge^1M$

$$d_J=J(d)=\sum_{i=1}^8J\left(\frac{\partial}{\partial x_i}\right)dx_i\\ =J\left(\frac{\partial}{\partial x_1}\right)dx_1+J\left(\frac{\partial}{\partial x_2}\right)dx_2+J\left(\frac{\partial}{\partial x_3}\right)dx_3+J\left(\frac{\partial}{\partial x_4}\right)dx_4+J\left(\frac{\partial}{\partial x_5}\right)dx_5+J\left(\frac{\partial}{\partial x_6}\right)dx_6+J\left(\frac{\partial}{\partial x_7}\right)dx_7\\ +J\left(\frac{\partial}{\partial x_8}\right)dx_8$$

$$d_JL=$$

$$\left(B^2\cos\theta\left(\frac{\partial L}{\partial x_5}\right)+B^2\sin\theta\left(\frac{\partial L}{\partial x_6}\right)\right)dx_1+\left(B^2\cos\theta\left(\frac{\partial L}{\partial x_6}\right)+B^2\sin\theta\left(\frac{\partial L}{\partial x_5}\right)\right)dx_2+\left(-B^2\cos\theta\left(\frac{\partial L}{\partial x_7}\right)+B^2\sin\theta\left(\frac{\partial L}{\partial x_8}\right)\right)dx_3+\\ \left(-B^2\cos\theta\left(\frac{\partial L}{\partial x_8}\right)+B^2\sin\theta\left(\frac{\partial L}{\partial x_7}\right)\right)dx_4+\left(-B^{-2}\cos\theta\left(\frac{\partial L}{\partial x_1}\right)-B^{-2}\sin\theta\left(\frac{\partial L}{\partial x_2}\right)\right)dx_5+\\ \left(B^{-2}\cos\theta\left(\frac{\partial L}{\partial x_2}\right)-B^{-2}\sin\theta\left(\frac{\partial L}{\partial x_1}\right)\right)dx_6+\left(-B^{-2}\cos\theta\left(\frac{\partial L}{\partial x_3}\right)-B^{-2}\sin\theta\left(\frac{\partial L}{\partial x_4}\right)\right)dx_7+\\ \left(B^{-2}\cos\theta\left(\frac{\partial L}{\partial x_4}\right)-B^{-2}\sin\theta\left(\frac{\partial L}{\partial x_3}\right)\right)dx_8$$

$$\text{Let } \phi_L=-d(Jd)=-d(d_JL)=-d\left(\left(B^2\cos\theta\left(\frac{\partial L}{\partial x_5}\right)+B^2\sin\theta\left(\frac{\partial L}{\partial x_6}\right)\right)dx_1+\left(B^2\cos\theta\left(\frac{\partial L}{\partial x_6}\right)+B^2\sin\theta\left(\frac{\partial L}{\partial x_5}\right)\right)dx_2+\\ \left(-B^2\cos\theta\left(\frac{\partial L}{\partial x_7}\right)+B^2\sin\theta\left(\frac{\partial L}{\partial x_8}\right)\right)dx_3+\left(-B^2\cos\theta\left(\frac{\partial L}{\partial x_8}\right)+B^2\sin\theta\left(\frac{\partial L}{\partial x_7}\right)\right)dx_4+\\ \left(-B^{-2}\cos\theta\left(\frac{\partial L}{\partial x_1}\right)-B^{-2}\sin\theta\left(\frac{\partial L}{\partial x_2}\right)\right)dx_5+\left(B^{-2}\cos\theta\left(\frac{\partial L}{\partial x_2}\right)-B^{-2}\sin\theta\left(\frac{\partial L}{\partial x_1}\right)\right)dx_6+\\ \left(-B^{-2}\cos\theta\left(\frac{\partial L}{\partial x_3}\right)-B^{-2}\sin\theta\left(\frac{\partial L}{\partial x_4}\right)\right)dx_7+\left(B^{-2}\cos\theta\left(\frac{\partial L}{\partial x_4}\right)-B^{-2}\sin\theta\left(\frac{\partial L}{\partial x_3}\right)\right)dx_8\right)$$

$$\phi_L=-d(Jd)=-d(d_JL)$$

$$=\sum_{i=1}^8\left(B^2\cos\theta\left(\frac{\partial^2L}{\partial x_5\partial x_i}\right)+2B\cos\theta\left(\frac{\partial B}{\partial x_i}\right)\left(\frac{\partial}{\partial x_5}\right)+B^2\sin\theta\left(\frac{\partial^2L}{\partial x_6\partial x_i}\right)+2B\sin\theta\left(\frac{\partial B}{\partial x_i}\right)\left(\frac{\partial}{\partial x_6}\right)\right)dx_1\wedge dx_i\\ +\sum_{i=1}^8\left(-B^2\cos\theta\left(\frac{\partial^2L}{\partial x_6\partial x_i}\right)+2B\cos\theta\left(\frac{\partial B}{\partial x_i}\right)\left(\frac{\partial}{\partial x_6}\right)+B^2\sin\theta\left(\frac{\partial^2L}{\partial x_5\partial x_i}\right)+2B\sin\theta\left(\frac{\partial B}{\partial x_i}\right)\left(\frac{\partial}{\partial x_5}\right)\right)dx_2\wedge dx_i\\ +\sum_{i=1}^8\left(B^2\cos\theta\left(\frac{\partial^2L}{\partial x_7\partial x_i}\right)+2B\cos\theta\left(\frac{\partial B}{\partial x_i}\right)\left(\frac{\partial}{\partial x_7}\right)+B^2\sin\theta\left(\frac{\partial^2L}{\partial x_8\partial x_i}\right)+2B\sin\theta\left(\frac{\partial B}{\partial x_i}\right)\left(\frac{\partial}{\partial x_8}\right)\right)dx_3\wedge dx_i\\ +\sum_{i=1}^8\left(-B^2\cos\theta\left(\frac{\partial^2L}{\partial x_8\partial x_i}\right)+2B\cos\theta\left(\frac{\partial B}{\partial x_i}\right)\left(\frac{\partial}{\partial x_8}\right)+B^2\sin\theta\left(\frac{\partial^2L}{\partial x_7\partial x_i}\right)+2B\sin\theta\left(\frac{\partial B}{\partial x_i}\right)\left(\frac{\partial}{\partial x_7}\right)\right)dx_4\wedge dx_i\\ +\sum_{i=1}^8\left(-B^{-2}\cos\theta\left(\frac{\partial^2L}{\partial x_1\partial x_i}\right)+2B^{-3}\cos\theta\left(\frac{\partial B}{\partial x_i}\right)\left(\frac{\partial}{\partial x_1}\right)-B^2\sin\theta\left(\frac{\partial^2L}{\partial x_2\partial x_i}\right)+2B^{-3}\sin\theta\left(\frac{\partial B}{\partial x_i}\right)\left(\frac{\partial}{\partial x_2}\right)\right)dx_5\wedge dx_i\\ +\sum_{i=1}^8\left(B^{-2}\cos\theta\left(\frac{\partial^2L}{\partial x_2\partial x_i}\right)-2B^{-3}\cos\theta\left(\frac{\partial B}{\partial x_i}\right)\left(\frac{\partial}{\partial x_2}\right)+B^2\sin\theta\left(\frac{\partial^2L}{\partial x_1\partial x_i}\right)-2B^{-3}\sin\theta\left(\frac{\partial B}{\partial x_i}\right)\left(\frac{\partial}{\partial x_1}\right)\right)dx_6\wedge dx_i\\ +\sum_{i=1}^8\left(-B^{-2}\cos\theta\left(\frac{\partial^2L}{\partial x_3\partial x_i}\right)-2B^{-3}\cos\theta\left(\frac{\partial B}{\partial x_i}\right)\left(\frac{\partial}{\partial x_3}\right)-B^2\sin\theta\left(\frac{\partial^2L}{\partial x_4\partial x_i}\right)-2B^{-3}\sin\theta\left(\frac{\partial B}{\partial x_i}\right)\left(\frac{\partial}{\partial x_4}\right)\right)dx_7\wedge dx_i\\ +\sum_{i=1}^8\left(B^{-2}\cos\theta\left(\frac{\partial^2L}{\partial x_4\partial x_i}\right)-2B^{-3}\cos\theta\left(\frac{\partial B}{\partial x_i}\right)\left(\frac{\partial}{\partial x_4}\right)-B^2\sin\theta\left(\frac{\partial^2L}{\partial x_3\partial x_i}\right)-2B^{-3}\sin\theta\left(\frac{\partial B}{\partial x_i}\right)\left(\frac{\partial}{\partial x_3}\right)\right)dx_8\wedge dx_i$$

$$\text{Let } i_\lambda(\phi_L)=\phi_L(\lambda)=\phi_L\left(\sum_{i=1}^8X^i\frac{\partial}{\partial x_i}\right)$$

[illegible]

differential energy function

$$\begin{aligned}
& \cos \theta \left(\frac{\partial}{\partial t} \right) \left(B^2 \frac{\partial L}{\partial x_6} \right) + \sin \theta \left(\frac{\partial}{\partial t} \right) \left(B^2 \frac{\partial L}{\partial x_5} \right) + \left(\frac{\partial L}{\partial x_2} \right) = 0 \\
& - \cos \theta \left[X^1 \frac{\partial}{\partial x_i} + X^2 \frac{\partial}{\partial x_i} + X^3 \frac{\partial}{\partial x_3} + X^4 \frac{\partial}{\partial x_4} + X^5 \frac{\partial}{\partial x_5} + X^6 \frac{\partial}{\partial x_6} + X^7 \frac{\partial}{\partial x_7} + X^8 \frac{\partial}{\partial x_8} \right] B^2 \frac{\partial L}{\partial x_7} \\
& + \sin \theta \left[X^1 \frac{\partial}{\partial x_i} + X^2 \frac{\partial}{\partial x_i} + X^3 \frac{\partial}{\partial x_3} + X^4 \frac{\partial}{\partial x_4} + X^5 \frac{\partial}{\partial x_5} + X^6 \frac{\partial}{\partial x_6} + X^7 \frac{\partial}{\partial x_7} + X^8 \frac{\partial}{\partial x_8} \right] B^2 \frac{\partial L}{\partial x_8} + \frac{\partial L}{\partial x_3} dx_3 = 0 \\
& \cos \theta \left(\frac{\partial}{\partial t} \right) \left(B^2 \frac{\partial L}{\partial x_7} \right) + \sin \theta \left(\frac{\partial}{\partial t} \right) \left(B^2 \frac{\partial L}{\partial x_8} \right) + \left(\frac{\partial L}{\partial x_3} \right) = 0 \\
& \cos \theta \left[X^1 \frac{\partial}{\partial x_i} + X^2 \frac{\partial}{\partial x_i} + X^3 \frac{\partial}{\partial x_3} + X^4 \frac{\partial}{\partial x_4} + X^5 \frac{\partial}{\partial x_5} + X^6 \frac{\partial}{\partial x_6} + X^7 \frac{\partial}{\partial x_7} + X^8 \frac{\partial}{\partial x_8} \right] B^2 \frac{\partial L}{\partial x_8} \\
& + \sin \theta \left[X^1 \frac{\partial}{\partial x_i} + X^2 \frac{\partial}{\partial x_i} + X^3 \frac{\partial}{\partial x_3} + X^4 \frac{\partial}{\partial x_4} + X^5 \frac{\partial}{\partial x_5} + X^6 \frac{\partial}{\partial x_6} + X^7 \frac{\partial}{\partial x_7} + X^8 \frac{\partial}{\partial x_8} \right] B^2 \frac{\partial L}{\partial x_7} + \frac{\partial L}{\partial x_4} dx_4 = 0 \\
& \cos \theta \left(\frac{\partial}{\partial t} \right) \left(B^2 \frac{\partial L}{\partial x_8} \right) + \sin \theta \left(\frac{\partial}{\partial t} \right) \left(B^2 \frac{\partial L}{\partial x_7} \right) + \left(\frac{\partial L}{\partial x_4} \right) = 0 \\
& - \cos \theta \left[X^1 \frac{\partial}{\partial x_i} + X^2 \frac{\partial}{\partial x_i} + X^3 \frac{\partial}{\partial x_3} + X^4 \frac{\partial}{\partial x_4} + X^5 \frac{\partial}{\partial x_5} + X^6 \frac{\partial}{\partial x_6} + X^7 \frac{\partial}{\partial x_7} + X^8 \frac{\partial}{\partial x_8} \right] B^2 \frac{\partial L}{\partial x_1} \\
& - \sin \theta \left[X^1 \frac{\partial}{\partial x_i} + X^2 \frac{\partial}{\partial x_i} + X^3 \frac{\partial}{\partial x_3} + X^4 \frac{\partial}{\partial x_4} + X^5 \frac{\partial}{\partial x_5} + X^6 \frac{\partial}{\partial x_6} + X^7 \frac{\partial}{\partial x_7} + X^8 \frac{\partial}{\partial x_8} \right] B^2 \frac{\partial L}{\partial x_2} + \frac{\partial L}{\partial x_5} dx_5 = 0 \\
& \cos \theta \left(\frac{\partial}{\partial t} \right) \left(B^{-2} \frac{\partial L}{\partial x_1} \right) + \sin \theta \left(\frac{\partial}{\partial t} \right) \left(B^{-2} \frac{\partial L}{\partial x_2} \right) + \left(\frac{\partial L}{\partial x_5} \right) = 0 \\
& \cos \theta \left[X^1 \frac{\partial}{\partial x_i} + X^2 \frac{\partial}{\partial x_i} + X^3 \frac{\partial}{\partial x_3} + X^4 \frac{\partial}{\partial x_4} + X^5 \frac{\partial}{\partial x_5} + X^6 \frac{\partial}{\partial x_6} + X^7 \frac{\partial}{\partial x_7} + X^8 \frac{\partial}{\partial x_8} \right] B^2 \frac{\partial L}{\partial x_2} \\
& - \sin \theta \left[X^1 \frac{\partial}{\partial x_i} + X^2 \frac{\partial}{\partial x_i} + X^3 \frac{\partial}{\partial x_3} + X^4 \frac{\partial}{\partial x_4} + X^5 \frac{\partial}{\partial x_5} + X^6 \frac{\partial}{\partial x_6} + X^7 \frac{\partial}{\partial x_7} + X^8 \frac{\partial}{\partial x_8} \right] B^2 \frac{\partial L}{\partial x_1} + \frac{\partial L}{\partial x_6} dx_6 = 0 \\
& \cos \theta \left(\frac{\partial}{\partial t} \right) \left(B^{-2} \frac{\partial L}{\partial x_2} \right) + \sin \theta \left(\frac{\partial}{\partial t} \right) \left(B^{-2} \frac{\partial L}{\partial x_1} \right) + \left(\frac{\partial L}{\partial x_6} \right) = 0 \\
& - \cos \theta \left[X^1 \frac{\partial}{\partial x_i} + X^2 \frac{\partial}{\partial x_i} + X^3 \frac{\partial}{\partial x_3} + X^4 \frac{\partial}{\partial x_4} + X^5 \frac{\partial}{\partial x_5} + X^6 \frac{\partial}{\partial x_6} + X^7 \frac{\partial}{\partial x_7} + X^8 \frac{\partial}{\partial x_8} \right] B^2 \frac{\partial L}{\partial x_3} \\
& - \sin \theta \left[X^1 \frac{\partial}{\partial x_i} + X^2 \frac{\partial}{\partial x_i} + X^3 \frac{\partial}{\partial x_3} + X^4 \frac{\partial}{\partial x_4} + X^5 \frac{\partial}{\partial x_5} + X^6 \frac{\partial}{\partial x_6} + X^7 \frac{\partial}{\partial x_7} + X^8 \frac{\partial}{\partial x_8} \right] B^2 \frac{\partial L}{\partial x_4} + \frac{\partial L}{\partial x_7} dx_7 = 0 \\
& \cos \theta \left(\frac{\partial}{\partial t} \right) \left(B^{-2} \frac{\partial L}{\partial x_3} \right) + \sin \theta \left(\frac{\partial}{\partial t} \right) \left(B^{-2} \frac{\partial L}{\partial x_4} \right) + \left(\frac{\partial L}{\partial x_7} \right) = 0 \\
& \cos \theta \left[X^1 \frac{\partial}{\partial x_i} + X^2 \frac{\partial}{\partial x_i} + X^3 \frac{\partial}{\partial x_3} + X^4 \frac{\partial}{\partial x_4} + X^5 \frac{\partial}{\partial x_5} + X^6 \frac{\partial}{\partial x_6} + X^7 \frac{\partial}{\partial x_7} + X^8 \frac{\partial}{\partial x_8} \right] B^2 \frac{\partial L}{\partial x_4} \\
& - \sin \theta \left[X^1 \frac{\partial}{\partial x_i} + X^2 \frac{\partial}{\partial x_i} + X^3 \frac{\partial}{\partial x_3} + X^4 \frac{\partial}{\partial x_4} + X^5 \frac{\partial}{\partial x_5} + X^6 \frac{\partial}{\partial x_6} + X^7 \frac{\partial}{\partial x_7} + X^8 \frac{\partial}{\partial x_8} \right] B^2 \frac{\partial L}{\partial x_3} + \frac{\partial L}{\partial x_8} dx_8 = 0 \\
& \cos \theta \left(\frac{\partial}{\partial t} \right) \left(B^{-2} \frac{\partial L}{\partial x_4} \right) + \sin \theta \left(\frac{\partial}{\partial t} \right) \left(B^{-2} \frac{\partial L}{\partial x_3} \right) + \left(\frac{\partial L}{\partial x_8} \right) = 0
\end{aligned}$$

Thus

$$\begin{aligned}
& \cos \theta \left(\frac{\partial}{\partial t} \right) \left(B^2 \frac{\partial L}{\partial x_5} \right) + \sin \theta \left(\frac{\partial}{\partial t} \right) \left(B^2 \frac{\partial L}{\partial x_6} \right) + \left(\frac{\partial L}{\partial x_1} \right) = 0, \quad \cos \theta \left(\frac{\partial}{\partial t} \right) \left(B^2 \frac{\partial L}{\partial x_6} \right) + \sin \theta \left(\frac{\partial}{\partial t} \right) \left(B^2 \frac{\partial L}{\partial x_5} \right) + \left(\frac{\partial L}{\partial x_2} \right) = 0 \\
& \cos \theta \left(\frac{\partial}{\partial t} \right) \left(B^2 \frac{\partial L}{\partial x_7} \right) + \sin \theta \left(\frac{\partial}{\partial t} \right) \left(B^2 \frac{\partial L}{\partial x_8} \right) + \left(\frac{\partial L}{\partial x_3} \right) = 0, \quad \cos \theta \left(\frac{\partial}{\partial t} \right) \left(B^2 \frac{\partial L}{\partial x_8} \right) + \sin \theta \left(\frac{\partial}{\partial t} \right) \left(B^2 \frac{\partial L}{\partial x_7} \right) + \left(\frac{\partial L}{\partial x_4} \right) = 0 \\
& \cos \theta \left(\frac{\partial}{\partial t} \right) \left(B^{-2} \frac{\partial L}{\partial x_1} \right) + \sin \theta \left(\frac{\partial}{\partial t} \right) \left(B^{-2} \frac{\partial L}{\partial x_2} \right) + \left(\frac{\partial L}{\partial x_5} \right) = 0, \quad \cos \theta \left(\frac{\partial}{\partial t} \right) \left(B^{-2} \frac{\partial L}{\partial x_2} \right) + \sin \theta \left(\frac{\partial}{\partial t} \right) \left(B^{-2} \frac{\partial L}{\partial x_1} \right) + \left(\frac{\partial L}{\partial x_6} \right) = 0 \\
& \cos \theta \left(\frac{\partial}{\partial t} \right) \left(B^{-2} \frac{\partial L}{\partial x_3} \right) + \sin \theta \left(\frac{\partial}{\partial t} \right) \left(B^{-2} \frac{\partial L}{\partial x_4} \right) + \left(\frac{\partial L}{\partial x_7} \right) = 0, \quad \cos \theta \left(\frac{\partial}{\partial t} \right) \left(B^{-2} \frac{\partial L}{\partial x_4} \right) + \sin \theta \left(\frac{\partial}{\partial t} \right) \left(B^{-2} \frac{\partial L}{\partial x_3} \right) + \left(\frac{\partial L}{\partial x_8} \right) = 0 \quad (9)
\end{aligned}$$

4. Conclusions

The solutions of the Lagrangian equations (9) are named Conformal Lagrangian Dynamics on Contact 9- Manifolds determined by on the mechanical system triple $(\mathbf{TM}, \mathbf{g}, \mathbf{L})$ are the paths of vector field \mathbf{J} on \mathbf{M} .

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