- > restart:
- > with(DifferentialGeometry):
- = with(Tools): with(LinearAlgebra):
- > DGsetup([z, y, u[1], u[2]], [a], M, verbose);

The following coordinates have been protected:

$$[z, y, u_1, u_2, a]$$

The following vector fields have been defined and protected:

$$[D_z, D_y, D_u_1, D_u_2, D_a]$$

The following differential 1-forms have been defined and protected:

$$[dz, dy, du_1, du_2, da]$$

> $g := Matrix([[a^3, 0, 0, 0], [0, a^2, 0, 0], [0, 0, a, 0], [0, 0, 0, a]]);$

$$g := \begin{bmatrix} a^3 & 0 & 0 & 0 \\ 0 & a^2 & 0 & 0 \\ 0 & 0 & a & 0 \\ 0 & 0 & 0 & a \end{bmatrix}$$
 (2)

 $\mathbf{M} > h := MatrixInverse(g) :$

 $\mathbf{M} > A := map(evalDG, (ExteriorDerivative(g).h));$

$$A := \begin{bmatrix} \frac{3 \ da}{a} & 0 \ dz & 0 \ dz & 0 \ dz & 0 \ dz \\ 0 \ dz & \frac{2 \ da}{a} & 0 \ dz & 0 \ dz \\ 0 \ dz & 0 \ dz & \frac{da}{a} & 0 \ dz \\ 0 \ dz & 0 \ dz & 0 \ dz & \frac{da}{a} \end{bmatrix}$$

$$(3)$$

 $\mathbf{M} > t[1] := \frac{da}{a}$

$$t_1 := \frac{da}{a} \tag{4}$$

$$\mathbf{M} > t[8] := \frac{1}{4} I y^2 dz - \frac{1}{4} I z^2 dy + \left(-\frac{1}{2} z - \frac{1}{2} y\right) du_1 + \frac{1}{4} du_2:$$

M >
$$t[9] := -\frac{1}{2} Iy dz + \frac{1}{2} Iz dy + \frac{1}{2} du_1$$
:

M > V := Vector([t[8], t[9], dz, dy]):

 $\mathbf{M} > W \coloneqq g.V$:

M > FD := FrameData([t[1], W[1], W[2], W[3], W[4]], N) :

M > $DGsetup(FD, [E], [alpha[1], sigma, rho, zeta, <math>\zeta^{\#}], verbose);$ The following coordinates have been protected: