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> restart :
> with(DifferentialGeometry) :
> with(Tools) :
> DGsetup( [z, y, u[1], u[2]], M, verbose);
      The following coordinates have been protected:
              [z, y, u1, u2]
      The following vector fields have been defined and protected:
              [Dz, Dy, Du1, Du2]
      The following differential 1-forms have been defined and protected:
              [dz, dy, du1, du2]
      frame name: M
(1)

M > L := evalDG(Dz + I·y· Du[1] + I·(2·z·y + y2)·Du2);
      L := Dz + Iy Du1 + Iy (2z + y) Du2
(2)

M > L# := evalDG(Dy - I·z· Du[1] - I·(2·z·y + z2)·Du2);
      L# := Dy - Iz Du1 - Iz (2y + z) Du2
(3)

M > T := I·LieBracket(L, L#);
      T := I (-2 I Du1 + (-4 Iz - 4 Iy) Du2)
(4)

M > S := LieBracket(L, T);
      S := 4 Du2
(5)

M > LieBracket(L#, T);
      4 Du2
(6)

M > Fr := FrameData([S, T, L, L#], N);
      Fr := [[E2, E3] = -E1, [E2, E4] = -E1, [E3, E4] = -I E2]
(7)

M > DGsetup(Fr, [E], [sigma[0], rho[0], zeta[0], ζ#[0]], verbose);
      The following coordinates have been protected:
              [z, y, u1, u2]
      The following vector fields have been defined and protected:
              [E1, E2, E3, E4]
      The following differential 1-forms have been defined and protected:
              [σ0, ρ0, ζ0, ζ#0]
      frame name: N
(8)

N > ExteriorDerivative(sigma[0]);
      ρ0 ∧ ζ0 + ρ0 ∧ ζ#0
(9)

N > ExteriorDerivative(rho[0]);
      I ζ0 ∧ ζ#0
(10)

N > ExteriorDerivative(zeta[0]);
      0 σ0 ∧ ρ0
(11)

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$$\mathbf{N} > DGinfo("CurrentFrame"); \quad N \quad (12)$$

$$\mathbf{N} > ChangeFrame(M); \quad N \quad (13)$$

$$\mathbf{M} > DualBasis([S, T, L, L^\#]);$$

$$\left[\frac{1}{4} Iy^2 dz - \frac{1}{4} Iz^2 dy + \left(-\frac{1}{2} z - \frac{1}{2} y \right) du_1 + \frac{1}{4} du_2, -\frac{1}{2} Iy dz + \frac{1}{2} Iz dy + \frac{1}{2} du_1, dz, \right. \\ \left. dy \right] \quad (14)$$

$$\mathbf{M} >$$