

By definition, $(\mathbf{b}, \hat{\mathbf{s}}, \hat{\boldsymbol{\rho}})$ is orthogonal system.

From eq. (49),

$$\frac{d}{dt}(\mathbf{u} + \mathbf{s}) = \frac{e}{m} \mathbf{E} - \Omega s \hat{\boldsymbol{\rho}} \quad (49)$$

$\mathbf{s} \cdot (49) :$

$$\mathbf{s} \cdot \frac{d}{dt}(\mathbf{u} + \mathbf{s}) = \frac{e}{m} \mathbf{s} \cdot \mathbf{E} - \Omega s \mathbf{s} \cdot \hat{\boldsymbol{\rho}} \quad (a1)$$

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0 (orthogonal)

$$\rightarrow u \mathbf{s} \cdot \frac{d\mathbf{b}}{dt} + \frac{d}{dt} \frac{1}{2} s^2 = \frac{e}{m} \mathbf{s} \cdot \mathbf{E} \quad (50)$$

$$\rightarrow \frac{1}{B} \frac{d}{dt} \frac{1}{2} m s^2 = -\frac{\mu}{B} \mathbf{s} \cdot \frac{d\mathbf{b}}{dt} + \frac{e}{B} \mathbf{s} \cdot \mathbf{E}$$

$$\rightarrow \frac{d\mu}{dt} = -\frac{\mu}{B} \frac{dB}{dt} - \frac{\mu}{B} \mathbf{s} \cdot \frac{d\mathbf{b}}{dt} + \frac{e}{B} \mathbf{s} \cdot \mathbf{E}$$

$\mathbf{v} \cdot (49) :$

$$\mathbf{v} \cdot \frac{d}{dt}(\mathbf{u} + \mathbf{s}) = \frac{e}{m} \mathbf{v} \cdot \mathbf{E} - \Omega s \mathbf{v} \cdot \hat{\boldsymbol{\rho}} \quad (a2)$$

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0 (orthogonal)

$$\rightarrow \frac{d}{dt} \frac{1}{2} m v^2 = e \mathbf{v} \cdot \mathbf{E} \quad (51)$$

$$\rightarrow \frac{dU}{dt} = e \frac{d\Phi}{dt} + e \mathbf{v} \cdot \left(-\nabla \Phi - \frac{1}{c} \frac{\partial \mathbf{A}}{\partial t} \right)$$

$$\rightarrow \frac{dU}{dt} = e \frac{\partial \Phi}{\partial t} + e \mathbf{v} \cdot \nabla \Phi + e \mathbf{v} \cdot \left(-\nabla \Phi - \frac{1}{c} \frac{\partial \mathbf{A}}{\partial t} \right)$$

$$\rightarrow \frac{dU}{dt} = e \frac{\partial \Phi}{\partial t} - \frac{e}{c} \mathbf{v} \cdot \frac{\partial \mathbf{A}}{\partial t}$$

\nearrow *errata in the book

$\hat{\boldsymbol{\rho}} \cdot (49) :$

$$\hat{\boldsymbol{\rho}} \cdot \frac{d}{dt}(\mathbf{u} + \mathbf{s}) = \frac{e}{m} \hat{\boldsymbol{\rho}} \cdot \mathbf{E} - \Omega s \hat{\boldsymbol{\rho}} \cdot \hat{\boldsymbol{\rho}} \quad (a3)$$

We need to be careful to manipulate LHS; RHS is just as it is. Considering orthogonal system, it can be described as

$$u \hat{\boldsymbol{\rho}} \cdot \frac{d\mathbf{b}}{dt} + s \hat{\boldsymbol{\rho}} \cdot \frac{d\hat{\mathbf{s}}}{dt} \quad (a4)$$

By definition from eq. (47), the second term of (a4) can be expressed by

$$s \hat{\boldsymbol{\rho}} \cdot \frac{d\hat{\mathbf{s}}}{dt} = s \hat{\boldsymbol{\rho}} \cdot \frac{d}{dt} (\mathbf{e}_2 \cos \gamma - \mathbf{e}_3 \sin \gamma) \quad (a5)$$

$$= s \frac{d\gamma}{dt} \hat{\boldsymbol{\rho}} \cdot (-\mathbf{e}_2 \sin \gamma - \mathbf{e}_3 \cos \gamma) + \left(s \cos \gamma \hat{\boldsymbol{\rho}} \cdot \frac{d\mathbf{e}_2}{dt} - s \sin \gamma \hat{\boldsymbol{\rho}} \cdot \frac{d\mathbf{e}_3}{dt} \right)$$

$$= -s \frac{d\gamma}{dt} + s \left(\cos^2 \gamma \mathbf{e}_3 \cdot \frac{d\mathbf{e}_2}{dt} - \sin^2 \gamma \mathbf{e}_2 \cdot \frac{d\mathbf{e}_3}{dt} \right)$$

For next step and the derivation of last line of (a5), we need to know following vector identities :

$$\mathbf{e}_i \cdot \frac{d\mathbf{e}_i}{dt} = \frac{1}{2} \frac{d}{dt} (\mathbf{e}_i \cdot \mathbf{e}_i) \stackrel{\text{orthogonal system, unit vector}}{=} \frac{d}{dt} 1 = 0 \quad (\text{a6})$$

$$\begin{aligned} \frac{d}{dt} (\mathbf{e}_2 \cdot \mathbf{e}_3) &= 0 \\ \rightarrow \frac{d\mathbf{e}_2}{dt} \cdot \mathbf{e}_3 + \mathbf{e}_2 \cdot \frac{d\mathbf{e}_3}{dt} &= 0 \\ \rightarrow \frac{d\mathbf{e}_2}{dt} \cdot \mathbf{e}_3 &= -\mathbf{e}_2 \cdot \frac{d\mathbf{e}_3}{dt} \end{aligned} \quad (\text{a7})$$

Therefore, with (a7), (a5) can be

$$s \hat{\boldsymbol{\rho}} \cdot \frac{d\hat{\mathbf{s}}}{dt} = -s \frac{d\gamma}{dt} + s \mathbf{e}_3 \cdot \frac{d\mathbf{e}_2}{dt} \quad (\text{a8})$$

Finally, (a3) with (a4) and (a8) becomes,

$$\frac{d\gamma}{dt} = \Omega + \mathbf{e}_3 \cdot \frac{d\mathbf{e}_2}{dt} - \frac{u}{s} \hat{\boldsymbol{\rho}} \cdot \frac{d\mathbf{b}}{dt} - \frac{e}{ms} \hat{\boldsymbol{\rho}} \cdot \mathbf{E} \quad (\text{52})$$

