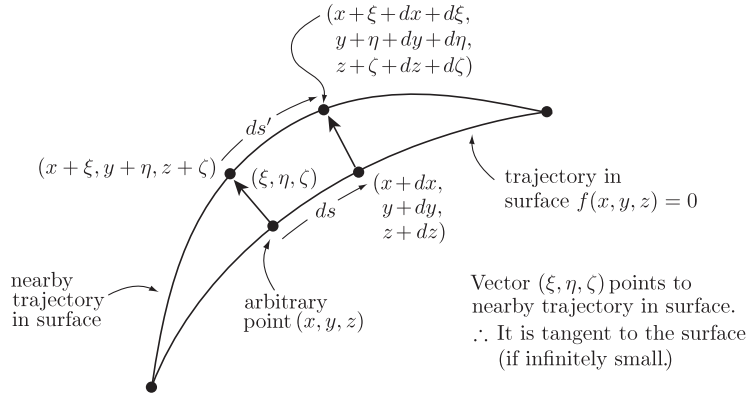


The details for those who want them:



Compare corresponding lengths on two curves and find

$$ds' - ds = (\dot{x}\dot{\xi} + \dot{y}\dot{\eta} + \dot{z}\dot{\zeta}) ds \quad \text{where } \dot{} = d/ds$$

$$\begin{aligned} \text{since } (ds')^2 &= [(x + \xi + dx + d\xi) - (x + \xi)]^2 + \dots = (dx + d\xi)^2 + \dots \\ &= (dx^2 + 2 dx d\xi + d\xi^2) + \dots \\ &= \underbrace{(dx^2 + dy^2 + dz^2)}_{ds^2} + 2 dx d\xi + 2 dy d\eta + 2 dz d\zeta \text{ in 2}^{\text{nd}} \text{ order quantities} \\ &= ds^2 \left(1 + 2 \frac{dx}{ds} \cdot \frac{d\xi}{ds} + \dots \right) = ds^2 (1 + 2 \dot{x}\dot{\xi} + \dots) \\ \therefore ds' &= ds(1 + \dot{x}\dot{\xi} + \dots) \quad \therefore ds' - ds = (\dot{x}\dot{\xi} + \dots) ds \end{aligned}$$

The condition for the motion to be force free, excepting the constraint to a surface $f(x, y, z)$,

$$m(a_x, a_y, a_z) = m \left(\frac{d^2x}{dt^2}, \frac{d^2y}{dt^2}, \frac{d^2z}{dt^2} \right) = \lambda \underbrace{\left(\frac{\partial f}{\partial x}, \frac{\partial f}{\partial y}, \frac{\partial f}{\partial z} \right)}_{\text{orthogonal to surface}}$$

is

$$\boxed{\begin{array}{l} (x(s), y(s), z(s)) \\ \text{has extremal length} \end{array} \Leftrightarrow \begin{array}{l} (a_x, a_y, a_z) \text{ is orthogonal to} \\ \text{the surface tangent vector } (\xi, \eta, \zeta) \end{array}}$$

The condition follows since the variation $\delta \int ds$ must vanish if the curve is extremal in length (a geodesic);

$$\begin{aligned} \delta \int ds &= \underbrace{\int ds' - \int ds}_{\text{same start and finish}} = \int (\dot{x}\dot{\xi} + \dot{y}\dot{\eta} + \dot{z}\dot{\zeta}) ds \\ &= \underbrace{\int \frac{d}{ds} (\dot{x}\xi + \dots) ds}_{(\dot{x}\xi + \dots)|_{\text{start}}^{\text{end}} = 0 \text{ since } (\xi, \eta, \zeta)(\text{start}) = (\xi, \eta, \zeta)(\text{end}) = 0} - \underbrace{\int (\xi\ddot{x} + \eta\ddot{y} + \zeta\ddot{z}) ds}_{\text{vanishes in general if } (\ddot{x}, \ddot{y}, \ddot{z}) \text{ orthogonal to } (\xi, \eta, \zeta)} \end{aligned}$$

The orthogonality of $(\ddot{x}, \ddot{y}, \ddot{z})$ to (ξ, η, ζ) implies the orthogonality of (a_x, a_y, a_z) to (ξ, η, ζ) because constrained motion has constant kinetic energy, and hence $s \propto t$.

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