Available online at http://www.journalcra.com

International Journal of Current Research
Vol. 18, Issue, 03, pp.36464-36469, March, 2026
DOI: https://doi.org/10.24941/ijcr.50267.03.2026

INTERNATIONAL JOURNAL OF CURRENT RESEARCH

ISSN: 0975-833X

RESEARCH ARTICLE

EFFECT OF RELATIVISTIC CORRECTIONS ON THE MOTION OF A GRAVITATING GYROSTAT

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ARTICLE INFO

Article History:
Received 15th December, 2025
Received in revised form
25th January, 2026
Accepted 18th February, 2026
Published online 29th March, 2026

Keywords:

Spin–Orbit Coupling, Relativistic Torque, Gravitomagnetic Influences, Spacecraft Dynamics, Astrophysics,

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ABSTRACT

The classical theory of gyrostat motion in a gravitational environment is often articulated within Newtonian mechanics by Euler–Poisson equations. Nevertheless, when velocities approach relativistic thresholds or when the gravitational field is sufficiently intense, relativistic corrections must be incorporated. In this study, we formulate a mathematical framework that characterizes the motion of a gravitational gyrostat, incorporating relativistic corrections derived from the post-Newtonian approximation of general relativity. The relativistic alteration of the rotational equations of motion is obtained by integrating spin–orbit coupling, relativistic torque, and gravitomagnetic influences. Energy techniques and perturbation theory are used to look at how stable steady rotations are. The study explores that relativistic corrections add new precession terms and change the criteria for stability at equilibrium. These effects are important for astrophysical objects like rotating satellites, compact stars, and spinning spacecraft that are in strong gravitational fields.

Citation: Dr. Bhola Nath Thakur. 2026. "Effect of Relativistic Corrections on the Motion of a Gravitating Gyrostat..". ***International Journal of Current Research, 18, (03), 36464-36469.***

INTRODUCTION

The study of how spinning rigid bodies move when there are gravitational forces acting on them is a classic issue in mechanics that has uses in spacecraft dynamics, astrophysics, and celestial mechanics (1). A gyrostat is a solid object with internal rotors that generate more angular momentum. These kinds of systems can be used to make models of satellites with reaction wheels, planets that spin with internal motion, and other astronomical bodies. The Euler–Poisson equations govern the movement of a gyrostat in a gravitational field in Newtonian mechanics (2,3). These equations show how gravitational torque changes angular momentum and orientation over time. Newtonian mechanics, on the other hand, considers that interactions happen instantly and does not consider relativistic effects. General relativity posits that gravity is not a force but a manifestation of space time curvature induced by matter and energy (4). Einstein's field equations, which connect space time geometry to energy–momentum distribution, tell us how bodies move in a gravitational field. The post-Newtonian approximation allows for the inclusion of relativistic effects when objects move slowly relative to the speed of light and gravitational fields are weak. This approximation adds corrections that are proportional to powers of v/c.(5)

When things are spinning, these changes cause several things to happen: relativistic spin-orbit coupling

- Forces of gravitomagnetism
- Relativistic precession
- Extra torque terms

These kinds of changes change the traditional rotational dynamics of gyrostats. Research on rotating bodies in relativity indicates that relativistic torques can induce supplementary precession, contingent upon the alignment of the body's primary axes. The objective of this study is to formulate a mathematical model for the motion of a gravitational gyrostat, incorporating relativistic corrections, and to examine the stability of its uniform motion (6-7).

A classical gyrostat's mathematical model: **Classical Mathematical Model of a Gyrostat:** A gyrostat is a mechanical system consisting of a rigid body that contains one or more internal rotors. These rotors spin inside the body and produce additional angular momentum. Because of this internal motion, the rotational dynamics of a gyrostat differ from those of an ordinary rigid body. Gyrostats are widely used as theoretical models in rigid body dynamics, spacecraft attitude control, celestial mechanics, and satellite stabilization (8). Mathematically, the motion of a gyrostat is described using Euler's equations of rotational motion together with additional terms representing the internal rotor momentum.

Coordinate System and Angular Velocity

Consider a rigid body with a fixed point O. A body-fixed coordinate system (e_1,e_2,e_3) is attached to the body and rotates with it. The axes of this coordinate system are chosen along the principal axes of inertia of the body(9).

Let the angular velocity of the body be

$\omega = (\omega_1, \omega_2, \omega_3)$ ....(1)

where, ω_1 is the angular velocity component about the first principal axis, ω_2 is the angular velocity component about the second principal axis, ω_3 is the angular velocity component about the third principal axis. The angular velocity vector describes how fast and in what direction the body rotates.

Moments of Inertia: The rotational resistance of the body is determined by the moments of inertia: I_1, I_2, I_3

These correspond to the principal axes of the rigid body. The inertia tensor in the body frame is therefore compactly

$$I = \begin{pmatrix} I_1 & 0 & 0 \\ 0 & I_2 & 0 \\ 0 & 0 & I_3 \end{pmatrix} \quad (2)$$

Or compactly , $I=\mathrm{diag}(I_1, I_2, I_3)$ (3)

This diagonal form occurs because the coordinate system is aligned with the principal axes of inertia. So, in Large inertia → body resists rotation strongly, and in Small inertia → body rotates more easily(10).

Gyrostatic Momentum from Internal Rotors: Unlike a simple rigid body, a gyrostat contains internal rotors spinning with constant angular momentum.

Let $h=(h_1,h_2,h_3)$ represent the gyrostatic momentum vector produced by these rotors.

Each component represents the rotor contribution along a principal axis:

Each component represents the rotor contribution along a principal axis:

- h_1 : rotor momentum along the axis e_1
- h_2 : rotor momentum along the axis e_2
- h_3 : rotor momentum along the axis e_3

The rotor spins independently of the rigid body, so its angular momentum adds directly to the body's angular momentum. Thus, the gyrostatic momentum is constant in the body frame (11).

Total Angular Momentum of the Gyrostat: The total angular momentum of the system consists of two parts:

- Rigid body rotational momentum
- Internal rotor momentum

The rigid body momentum is $I\omega$

Therefore, the total angular momentum vector is

$M = I\omega + h$ (4)

Explicitly, $$M = \begin{pmatrix} I_1\omega_1 + h_1 \\ I_2\omega_2 + h_2 \\ I_3\omega_3 + h_3 \end{pmatrix} \quad (5)$$

This equation shows that the internal rotors shift the effective angular momentum of the body(12).

Rotational Dynamics Equation: The fundamental equation governing the rotational motion of a rigid body is derived from

Newton's law for rotation: $\frac{dM}{dt} = \tau$ (6)

Where M is the angular momentum, and τ is the applied torque.
However, when expressed in the rotating body frame, the equation becomes

$$\frac{dM}{dt} + \omega \times M = \tau \quad (7)$$

This is known as the Euler equation of motion.

1. $\frac{dM}{dt}$, Rate of change of angular momentum in the body frame.
2. **2.** $\omega \times M$ represents the effect of the rotating coordinate system.
3. τ External torque acting on the body.

Thus, the equation states: The change in angular momentum plus the rotational transport term equals the external torque.(14)

Component Form of Euler–Gyrostat Equations

Substituting $M=I\omega+h$ into the motion equation gives

$$\frac{d}{dt}(I\omega + h) + \omega \times (I\omega + h) = \tau \quad (8)$$

Since h is constant,

$$\frac{d}{dt}(I\omega) + \omega \times (I\omega + h) = \tau \quad (9)$$

$$I_1\dot{\omega}_1 - (I_2 - I_3)\omega_2\omega_3 - h_2\omega_3 + h_3\omega_2 = \tau_1 \quad (10)$$

$$I_2\dot{\omega}_2 - (I_3 - I_1)\omega_3\omega_1 - h_3\omega_1 + h_1\omega_3 = \tau_2 \quad (11)$$

$$I_3\dot{\omega}_3 - (I_1 - I_2)\omega_1\omega_2 - h_1\omega_2 + h_2\omega_1 = \tau_3 \quad (12)$$

These are called the Euler–gyrostat equations (15).
Gravitational Torque: Now, consider the gyrostat moving in a gravitational field.

Let, $\gamma=(\gamma_1,\gamma_2,\gamma_3)$

be the unit vector pointing in the direction of gravity, expressed in the body frame. Let m be the mass of the body, g is the gravitational acceleration, and r is the vector from the pivot point to the center of mass.

Then the gravitational torque is

$$\tau = mg\,(r \times \gamma) \tag{13}$$

This torque arises because the center of mass is displaced from the pivot point.

The cross product $(r \times \gamma)$ determines the moment arm of the gravitational force.

Therefore

- If the center of mass lies directly below the pivot → torque is zero
- If it is displaced → gravitational torque causes rotation.

Orientation Dynamics (Poisson Equations)

The direction of gravity in the body frame changes as the body rotates.
Thus, the vector γ satisfies

$$\frac{d\gamma}{dt} = \gamma \times \omega \tag{14}$$

These are called the Poisson equations.

They describe how the gravitational direction evolves relative to the rotating body.

Complete Classical Gyrostat System

The full mathematical model consists ofEuler–Gyrostat Equations

$$\frac{d}{dt}(I\omega + h) + \omega \times (I\omega + h) = mg(r \times \gamma) \tag{15}$$

Poisson Equations, $\frac{d\gamma}{dt} = \gamma \times \omega$ (16)

Together, these equations form a six-dimensional nonlinear dynamical system describing the motion of a gravitating gyrostat.

Importance of the Model

This mathematical framework is fundamental for studying:

- Stability of rotating satellites
- Spacecraft attitude dynamics
- Motion of spinning celestial bodies
- Control of gyroscopic stabilization systems.

It also provides the starting point for introducing relativistic corrections, which modify the torque and angular momentum equations in strong gravitational fields (16).

Poisson Equations for Direction

$$\frac{d\gamma}{dt} = \gamma \times \omega \tag{17}$$

These equations explain how the gyrostat moves in a classical way.

Approximation After Newton: When you utilize the post-Newtonian approximation, the field of gravity isn't very strong. The speed of bodies is substantially slower than the speed of light $v \ll c$ v ≪ c, where v is the body's normal speed and c is the speed of light(17).In these circumstances, the equations of motion can be expressed as a series in powers of $\frac{1}{c^2}$This makes a rectification hierarchy: Newtonian mechanics → main phrase, First post-Newtonian correction: order $\frac{1}{c^2}$, More corrections: $\frac{1}{c^4}, \frac{1}{c^6}$and so on So, the post-Newtonian framework connects Newtonian gravity and general relativity.

The Force's Relativistic Expansion: In Newtonian mechanics, the gravitational force exerted on an object is

$$F_N = -\frac{GMm}{r^2}\, r \tag{18}$$

Where G is the gravitational constant, M is the mass that makes the gravitational field, m is the mass of the body that is traveling, r is the space between them, and r^, the unit radial vector is 5^. In the post-Newtonian framework, the total force is expressed as

$$F = F_N + \frac{1}{c^2} F_{PN} \tag{19}$$

This equation shows that the entire gravitational force is made up of two parts:

Newtonian Force FN, Newton's law says that this is the normal gravitational pull. It is in charge when speeds are low and Gravitational fields aren't very strong. This term alone adequately represents the motion for most mechanical systems that people use every day(18).

Relativistic Correction F_{PN} : The second term is the first change to Newtonian gravity that takes relativity into account. The factor multiplies it by$\frac{1}{c^2}$, which makes it a lot smaller than the Newtonian term. But even though it's modest, it matters in computations of orbits with high accuracy, in very powerful fields of gravity, for the long-term development of dynamic systems. This adjustment occurs because gravity transmits through the curvature of space-time instead of immediate forces (19,20).

The Physical Basis of Relativistic Corrections: The relativistic correction 5_{5N} includes contributions from multiple physical phenomena anticipated by general relativity.

Gravity that depends on speed: In general relativity, the gravitational interaction is contingent not only on the position but also on the velocity of the moving body. So, more terms that are proportional to v^2 show up in the equations of motion. These changes change how orbits and rotations work (21).

Time Dilation Due to Gravity: General relativity says that time moves more slowly in areas with substantial gravity. This effect changes the rate of dynamic evolution since the motion equations depend on time derivatives. This makes changes in both: motion that moves things move in a circle (22).

The bending of spacetime: In Newtonian mechanics, gravity operates throughout flat space. General relativity, on the other hand, says that gravity is the bending of space and time. In curved spacetime, geodesics are the shortest paths that particles follow. The post-Newtonian correction FPNshows how this curvature affects motion in math (23).

Effects of Relativity on Extended Bodies: The relativistic corrections for a point particle are only based on its mass and speed. But a gyrostat is a long body with an interior structure; thus, there are more relativistic effects. These include donations from: the distribution of mass, internal momentum, and motion of the internal rotor. So, the relativistic force must have terms that have to do with the body's spin and how its parts move(24).

Contributions of Spin

In relativity, rotating objects have spin angular momentum that affects the gravitational field. This causes something called spin–orbit coupling to happen. This is what spin-orbit coupling means: The body's rotation affects its orbital motion. The gravitational field influences how the body spins. This is especially important for a gyrostat because the body has internal rotors that add to the angular momentum(25).

Interaction of Spin and Gravity

The gravitational field interacts with the body's spin vector S.The relativistic equation of motion for spin is$\frac{dS}{dt}$=$\Omega rel \times S$, where Ω is the relativistic precession frequency. This equation shows that the spin vector does not remain fixed but slowly rotates due to relativistic effects. This phenomenon is known as relativistic spin precession(26,27).

Influence of Internal Structure: Unlike a point mass, a gyrostat has an internal structure composed of: rigid body mass distribution, spinning rotors, and possible asymmetry in inertia. In relativistic mechanics, the internal structure affects the gravitational interaction through multipole moments. These include: mass monopole (total mass), quadrupole moment (shape of mass distribution), spin dipole (rotational momentum)(28). These structural effects modify the relativistic correction 5_{55}.

Importance for Gyrostat Dynamics: When relativistic corrections are included, the classical gyrostat equations must be modified. The new equations include: relativistic corrections to the gravitational force, relativistic torque acting on the rotating body, and coupling between orbital and rotational motion. These corrections lead to new physical phenomena such as: relativistic precession of the gyrostat, changes in steady rotational states, and modifications of stability conditions(29,30).

Order of Magnitude of Relativistic Corrections

The magnitude of relativistic corrections can be estimated using $\frac{GM}{C^2 r}$For Earth-orbiting satellites, this value is approximately 10^{-10}which is very small. However, for astrophysical systems such as neutron stars, black hole binaries, and relativistic pulsars, the corrections grow considerably greater and significantly alter the dynamics (31). The relativistic framework provides a systematic technique to extend Newtonian gyrostat dynamics to include features predicted by general relativity. By employing the post-Newtonian approximation, the gravitational force can be represented as a combination of the classical Newtonian force and relativistic correction terms. These adjustments originate from velocity-dependent gravitational effects, spacetime curvature, spin–gravity interaction, and the internal structure of the rotating body. For a gyrostat, the existence of internal rotors introduces additional angular momentum that interacts with the relativistic gravity field, leading to changed equations of motion and unexpected dynamical behaviour (32).

Corrections for rotational motion in relativity

Relativistic corrections add more torque words.

The new rotational equation is

$$\frac{dM}{dt} + \omega \times M = \tau_N + \frac{1}{c^2}\tau_R \qquad (20)$$

where • τ_N: classical gravitational torque • τ_R: relativistic torque.

Torque in Relativity

The relativistic torque comes from:

1. connection of spin and orbit
2. field of gravitomagnetism
3. The distribution of relativistic mass.

In the first post-Newtonian approximation,

$$\tau_R = \Omega_{\text{rel}} \times M \qquad (21)$$

where

$$\Omega_{\text{rel}} = \frac{3GM}{2c^2 r^3}\,(r \times v) \qquad (22)$$

This causes the gyrostat to precess even more

4.2 Effects of Gravitomagnetism: A rotating mass creates a gravitomagnetic field that is like magnetism in electromagnetic (33). This field adds more torque to things that are spinning. The gravitomagnetic acceleration is

$$a_{GM} = 2\,v \times B_g \qquad (23)$$

Where, $B_g = \nabla \times A_g$ (24)

The influence changes the durations of orbits and the way things rotate.

Altered Euler–Poisson Equations. Adding both classical and relativistic contributions produces

Rotational dynamics

$$\frac{d}{dt}(I\omega + h) + \omega \times (I\omega + h) = \tau_N + \frac{1}{c^2}\tau_R \quad (25)$$

Dynamics of orientation $\frac{d\gamma}{dt} = \gamma \times \omega$ (26)

These are the equations for the relativistic gyrostat

Motion that stays the same. When $\dot{\omega}=0$ and γ=constant, steady rotation happens. When you put the motion equations together, you get the conditions for equilibrium:

$$\omega \times (I\omega + h) = \tau_N + \frac{1}{c^2}\tau_R \quad (27)$$

Relativistic adjustments thus alter equilibrium states.

Analyzing Stability: Think about tiny changes

$$\omega = \omega_0 + \epsilon \quad (28)$$

Linearizing the equations yields

$$\frac{d\epsilon}{dt} = A\epsilon \quad (29)$$

where A is the matrix of stability. The eigenvalues of A influence how stable it is. Condition for stability: det(A−λI)=0. Relativistic corrections change the matrix coefficients, which in turn move the stability bounds.

Precession in Relativity: Relativistic dynamics adds more precession terms:

- Precession of Thomas$\Omega_T = \frac{1}{2c^2}(v \times a)$
- Precession of the Earth
- Dragging the frame: Thomas precession occurs because of repeated Lorentz transformations during curved motion. These influences change the direction of the gyrostat over time(34).

Uses of relativistic gyrostat dynamics are useful for

1. The dynamics of satellite attitude: Spacecraft with very high precision need relativistic adjustments to navigate.
2. Rotating Bodies in Astrophysics: Pulsars and rotating neutron stars act like relativistic gyrostats.
3. Systems of Two Stars: Spin–orbit coupling changes how orbits change over time. Tests of Gravity Experiments with gyroscopes, including measuring frame dragging (35).
4. An example using numbers: Think of a gyrostat that is going around the Earth. Parameters:

$M = 5.97 \times 10^{24}$ kg and $r = 7000$ km

Magnitude of relativistic correction $\frac{GM}{c^2 r} \sim 10^{-10}$

These corrections may seem modest, but they add up over time

DISCUSSION

Adding relativistic corrections makes the classical gyrostat dynamics very different.

Key results:

- more precision terms
- changed states of equilibrium
- changed the conditions for stability
- linking orbital and rotational motion

These effects become significant in systems with intense gravitational fields, such as neutron stars or relativistic binaries.

CONCLUSION

This research created a mathematical model for the dynamics of a gravitational gyrostat, incorporating relativistic adjustments through the post-Newtonian approximation. We generated and evaluated the relativistic extension of the Euler–Poisson equations. It was demonstrated that relativistic effects introduce additional torque and precession terms that affect the stability of steady rotations. Future work may encompass post-Newtonian adjustments of a higher order, computer simulations, chaotic dynamics in relativity coupling of gravitational waves. The theory provides a framework for examining rotating bodies in relativistic gravitational settings.

- More precision terms
- Changed states of equilibrium
- Changed the conditions for stability
- Linking orbital and rotational motion

These effects become significant in systems with intense gravitational fields, such as neutron stars or relativistic binaries.

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