

# Physical Parameter Reconstruction of Mass-spring System from its Frequencies and Modes

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**Abstract.** In this paper, an inverse eigenvalue problem of constructing the mass and spring matrices of the mass-spring system from the information of frequency(eigenvalue) and mode(eigenvector) is considered. The solvability of the problem is discussed. Furthermore numerical algorithms and some numerical experiments are given with applications to mass-spring vibrating system.

**Keywords:** Frequency, Mode, Inverse Eigenvalue problem, Mass-spring system

## 1. Introduction

Inverse problems in vibration of spring-mass systems aim to determine the physical parameters such as masses and spring constants from natural frequencies and modal data. These problems have important applications in vibration design, structural dynamic design, and structural physical parameter recognition<sup>[1-6,10]</sup>, because  $n$  degree of freedom mass-spring system may be thought of as finite-difference or finite-element approximations of continuous systems. Gladwell [10,11], Nylen [1], Ram[3,4], Zhou and Dai [9] had shown that inverse eigenvalue problems arising in classical vibration theory which the reconstruction of mass-spring system may be thought of as basic inverse vibration problem.

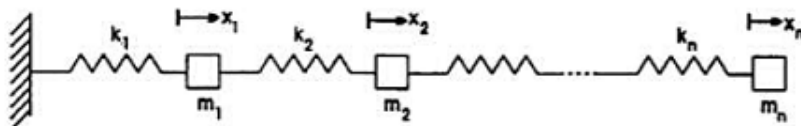


Figure 1: Spring-mass system fixed-free.

A linear  $n$  degree of freedom system of  $n$  point masses simply interconnected by springs (as Fig1 ) is characterized by the generalized eigenvalue problem

$$\lambda Mx = Kx \quad (1)$$

Where  $\lambda = \omega^2$ ,  $\omega$  is the nature frequency,  $x$  is the mode,  $M$  is the mass matrix, and  $K$  is the stiffness matrix as following

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$$M = \begin{bmatrix} m_1 & & & \\ & m_2 & & \\ & & \ddots & \\ & & & m_n \end{bmatrix}, \quad K = \begin{bmatrix} k_1 + k_2 & -k_2 & & & \\ -k_2 & k_2 + k_3 & -k_3 & & \\ & -k_3 & k_3 + k_4 & \ddots & \\ & & \ddots & \ddots & \\ & & & k_{n-1} + k_n & -k_n \\ & & & -k_n & k_n \end{bmatrix}$$

There are many important results on reconstruction a mass-spring system with given data<sup>[1,5,9-11]</sup>, for example, Ram and Gladwell have given the algorithms for constructing the physical parameters  $m_i$  and  $k_i$  with all or partial natural frequencies of system by constructing a Jacobi matrix.

In this paper, we focus on the reconstruction of mass-spring system with nature frequency and mode from the modified system. In section 2, we discuss the physical parameter reconstruction of two degree of freedom mass-spring system from the modified system. In section 3, we discuss the physical parameter reconstruction of  $n$  degree of freedom system by given two or three nature frequencies and corresponding modes. The solvability of the problem is discussed and some sufficient and necessary conditions for existence of the solution of this problem are proposed. Furthermore, Some numerical examples are given in Section 4.

## 2. The reconstruction of two degree of freedom system from the modified system

Considering the two degree of freedom mass-spring system

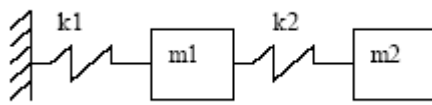


Fig.2 The original systems

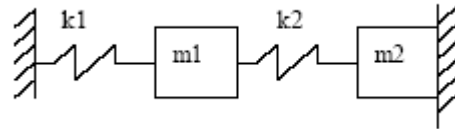


Fig.3 The modified systems with stiffness

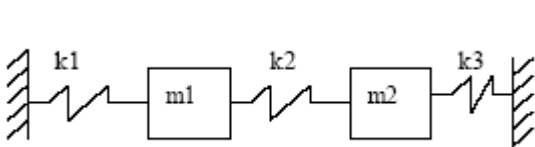


Fig.4 The modified systems with spring

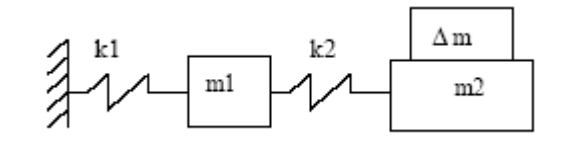


Fig.5 The modified systems with stiffness

The two degree of freedom mass-spring system is characterized  $\lambda Mx = Kx$  with

$$M = \begin{bmatrix} m_1 & 0 \\ 0 & m_2 \end{bmatrix}, \quad K = \begin{bmatrix} k_1 + k_2 & -k_2 \\ -k_2 & k_2 \end{bmatrix}$$

The eigen-equation of (1) is

$$|K - \lambda M| = m_1 m_2 \lambda^2 - [m_2 (k_1 + k_2) + m_1 k_2] \lambda + k_1 k_2 = 0 \quad (2)$$

with roots  $\lambda_1, \lambda_2$  satisfying

$$\lambda_1 + \lambda_2 = \frac{k_1 + k_2}{m_1} + \frac{k_2}{m_2} \quad (3)$$

$$\lambda_1 \lambda_2 = \frac{k_1 k_2}{m_1 m_2} \quad (4)$$

If only  $\lambda_1, \lambda_2$  are given, it can not reconstruction the four physical parameters  $m_1, m_2, k_1, k_2$  from (3) and (4). It needs the additional condition.

Here three ways are given as the additional condition. (1) The modified system by fixed the  $m_2$  (as Fig.3); (2) The modified system by adding a spring attaching the  $m_2$  (as Fig.4); (3) The modified system by adding a mass  $\Delta m$  attaching to the  $m_2$  (as Fig.5).

### (1) The modified system by fixed the last mass

It is easy to get the eigenvalue of the modified system (as fig.3)

$$\lambda^0 = \frac{k_1 + k_2}{m_1} \quad (5)$$

From (3) and (5) ,

$$0 < \lambda^0 < \lambda_1 + \lambda_2$$

So

$$\frac{k_2}{m_2} = \lambda_1 + \lambda_2 - \lambda^0 \quad (6-1)$$

$$\frac{k_1}{m_1} = \frac{\lambda_1 \lambda_2}{\lambda_1 + \lambda_2 - \lambda^0} \quad (6-2)$$

$$\frac{k_2}{m_1} = \frac{(\lambda^0 - \lambda_1)(\lambda_2 - \lambda^0)}{\lambda_1 + \lambda_2 - \lambda^0} \quad (6-3)$$

Therefore, (6) gives the relation between  $m_1$ ,  $m_2$ ,  $k_1$ ,  $k_2$ . If one of them is given (by experiment), others can be computed by (6).

### (2) The modified system by adding spring to the last mass

Considering the modified system by adding spring to the last mass (as fig.4). The mass and stiffness matrices of the modified system are

$$M = \begin{bmatrix} m_1 & 0 \\ 0 & m_2 \end{bmatrix}, \quad K = \begin{bmatrix} k_1 + k_2 & -k_2 \\ -k_2 & k_2 + k_3 \end{bmatrix}$$

From its generalized eigenvalue problem (1), the eigenvalues of the original system have the relation

$$\lambda_1 + \lambda_2 = \frac{k_1 + k_2}{m_1} + \frac{k_2}{m_2} \quad (7)$$

$$\lambda_1 \lambda_2 = \frac{k_1 k_2}{m_1 m_2} \quad (8)$$

Also, the eigenvalues  $\bar{\lambda}_1$ ,  $\bar{\lambda}_2$  of the modified system have the relation

$$\bar{\lambda}_1 + \bar{\lambda}_2 = \frac{k_1 + k_2}{m_1} + \frac{k_2 + k_3}{m_2} \quad (9)$$

$$\bar{\lambda}_1 \bar{\lambda}_2 = \frac{k_1 k_2 + k_1 k_3 + k_2 k_3}{m_1 m_2} \quad (10)$$

For simplicity, denote  $\lambda_1 = a$ ,  $\lambda_2 = b$ ,  $\bar{\lambda}_1 = c$ ,  $\bar{\lambda}_2 = d$  and  $k_3 = k$ .

From (7) - (10) ,

$$m_1 = \frac{kP^2}{(ad^2 + ac^2 + a^3 + bcd + 3adc + a^2b - 2a^2d - 2a^2c - c^2d - cd^2 - abc - abd)Q} \quad (11-1)$$

$$m_2 = \frac{k}{c + d - a - b} \quad (11-2)$$

$$k_1 = \frac{kabP}{(cd + a^2 - ac - ad)Q} \quad (11-3)$$

$$k_2 = \frac{kP}{2ac + 2ad + 2bc + 2bd - a^2 - 2ab - b^2 - c^2 - 2cd - d^2} \quad (11-4)$$

where  $P = a^2 + b^2 + ab + cd - ac - ad - bd - bc$ ,  $Q = b^2 + cd - bc - bd$ .

Therefore, if  $\lambda_1$ ,  $\lambda_2$  and  $\bar{\lambda}_1$ ,  $\bar{\lambda}_2$  are given, all the physical parameters of the original system from (11).

### (3) The modified system by adding a mass $\Delta m$ attaching to the last mass

Considering the modified system by adding mass  $\Delta m$  to the last mass (as fig.4). The mass and stiffness matrices of the modified system are

$$M = \begin{bmatrix} m_1 & 0 \\ 0 & m_2 + \Delta m \end{bmatrix}, K = \begin{bmatrix} k_1 + k_2 & -k_2 \\ -k_2 & k_2 \end{bmatrix}$$

Then the eigenvalues of modified system have the relation

$$\bar{\lambda}_1 + \bar{\lambda}_2 = \frac{k_1 + k_2}{m_1} + \frac{k_2}{m_2 + \Delta m} \quad (12)$$

$$\bar{\lambda}_1 \bar{\lambda}_2 = \frac{k_1 k_2}{m_1 (m_2 + \Delta m)} \quad (13)$$

denote  $\lambda_1 = a$ ,  $\lambda_2 = b$ ,  $\bar{\lambda}_1 = c$ ,  $\bar{\lambda}_2 = d$  and  $\Delta m = m$ .

Connecting (12) (13) with (3) (4), we have

$$m_2 = \frac{mcd}{ab - cd} \quad (14-1)$$

$$k_2 = \frac{mabcd(a + b - c - d)}{(ab - cd)^2} \quad (14-2)$$

$$m_1 = \frac{m_2 k_2^2}{m_2 k_2 (a + b) - k_2^2 - ab m_2^2} \quad (14-3)$$

$$k_1 = \frac{m_1 m_2 ab}{k_2} \quad (14-4)$$

Therefore, if  $\lambda_1, \lambda_2$ ,  $\bar{\lambda}_1, \bar{\lambda}_2$  and  $\Delta m$  are given, all the physical parameters of the original system from (14).

The three models can be summarized as the inverse eigenvalue problem: The reconstruction of the physical parameters of two degree of freedom system from its nature frequencies of the original and modified system.

### (4) The reconstruction form the nature frequencies and corresponding modes

The generalized eigenvalue problem (1) can be rewritten as the following standard eigenvalue problem

$$Dx = \lambda x \quad (15)$$

where

$$D = M^{-1}K \quad (16)$$

For two degree of freedom system,

$$D = \begin{bmatrix} a_1 & -b \\ -c & a_2 \end{bmatrix}$$

where

$$a_1 = \frac{k_1 + k_2}{m_1}, b = \frac{k_2}{m_1}, c = \frac{k_2}{m_2}, a_2 = \frac{k_2}{m_2} \quad (17)$$

If the eigenpairs  $\lambda_1, \varphi_1, \phi_2, \lambda_2$  are given which is satisfied with (15), rewriting into matrix form

$$D\phi = \phi\Lambda$$

where

$$\varphi = [\varphi_1 \quad \varphi_2], \Lambda = \text{diag}[\lambda_1 \quad \lambda_2]$$

then

$$D = \varphi\Lambda\varphi^{-1} \quad (18)$$

Also, from (17), we get

$$\frac{k_1}{m_1}, \frac{k_2}{m_1}, \frac{k_2}{m_2}$$

Similar as (6), we can get the physical parameters  $m_1, m_2, k_1, k_2$  if one of them is given.

### 3. The reconstruction of $n$ degree of freedom system from its a few nature frequencies and corresponding modes

The generalized eigenvalue problem (1) of  $n$  degree of freedom system can be rewritten as the following standard eigenvalue problem (15) with

$$D = M^{-1}K = \begin{bmatrix} \frac{k_1 + k_2}{m_1} & \frac{-k_2}{m_1} & & & \\ \frac{-k_2}{m_2} & \frac{k_2 + k_3}{m_2} & \frac{-k_3}{m_2} & & \\ & \frac{-k_3}{m_3} & \frac{k_3 + k_4}{m_3} & \ddots & \\ & & \ddots & \frac{k_{n-1} + k_n}{m_{n-1}} & \frac{-k_n}{m_{n-1}} \\ & & & \frac{-k_n}{m_n} & \frac{k_n}{m_n} \end{bmatrix} \quad (19)$$

$$= \begin{bmatrix} a_1 & -b_1 & & & \\ -c_1 & a_2 & -b_2 & & \\ & -c_2 & \ddots & \ddots & \\ & & \ddots & a_{n-1} & -b_{n-1} \\ & & & -c_{n-1} & a_n \end{bmatrix} \quad (20)$$

where

$$a_i = \frac{k_i + k_{i+1}}{m_i}; b_i = \frac{k_{i+1}}{m_i}; c_i = \frac{k_{i+1}}{m_{i+1}}; k_{n+1} = 0, b_n = c_n = 0 \quad (i = 1, 2, \dots, n) \quad (21)$$

If matrix  $D$  is known, we can get all the physical parameters of the system by (21).

#### Algorithm 1

(1) If  $m_1$  given, from  $a_1, b_1$ ,

$$k_2 = m_1 b_1, k_1 = m_1 a_1 - k_2 = m_1 (a_1 - b_1)$$

(2) From  $c_1, b_2$ , we get  $m_2, k_3$

$$m_2 = \frac{k_2}{c_1} = m_1 \frac{b_1}{c_1}, \quad k_3 = m_2 b_2 = m_1 \frac{b_1}{c_1} b_2$$

(3) From  $c_{i-1}, b_i$ , we get  $m_i, k_{i+1}$

$$m_i = \frac{k_i}{c_{i-1}} = m_1 \prod_{j=1}^{i-1} \frac{b_j}{c_j}, \quad k_{i+1} = m_i b_i = m_1 b_i \prod_{j=1}^{i-1} \frac{b_j}{c_j} \quad (i = 3, 4, \dots, n-2)$$

(4) From  $c_{n-2}, b_{n-1}$ , we get  $m_{n-1}, k_n$

$$m_{n-1} = \frac{k_{n-1}}{c_{n-2}} = m_1 \prod_{j=1}^{n-2} \frac{b_j}{c_j}, \quad k_n = m_{n-1} b_{n-1} = m_1 b_{n-1} \prod_{j=1}^{n-2} \frac{b_j}{c_j}$$

(5) From  $a_n$ , we get  $m_n$

$$m_n = \frac{k_n}{a_n} = m_1 \frac{b_{n-1}}{a_n} \prod_{j=1}^{n-2} \frac{b_j}{c_j}$$

Note that the tri-diagonal matrix  $D$  in (20) can be rewritten into Jacobi matrix  $J$  by similar transform as following

Choosing the nonsingular matrix

$$P = \begin{bmatrix} 1 & & & \\ & p_1 & & \\ & & \ddots & \\ & & & p_{n-1} \end{bmatrix}$$

where

$$p_i = \sqrt{\frac{c_1 c_2 \cdots c_i}{b_1 b_2 \cdots b_i}} \quad (i = 1, 2, \dots, n-1)$$

Do similar transform  $x = Py$  to (15),

$$Jy = \lambda y$$

Where  $J = P^{-1}DP$  is symmetric tri-diagonal matrix, which has the same eigenvalues of matrix  $D$ . Therefore, the problem can be summarized as the inverse eigenvalue problem of symmetric tri-diagonal matrix.

Also, the generalized eigenvalue problem (1) can be rewritten into standard eigenvalue problem

$$Ay = \lambda y \quad (22)$$

where

$$A = M^{-\frac{1}{2}} K M^{-\frac{1}{2}} = \begin{bmatrix} \frac{k_1 + k_2}{m_1} & \frac{-k_2}{\sqrt{m_1 m_2}} & & & \\ \frac{-k_2}{\sqrt{m_1 m_2}} & \frac{k_2 + k_3}{m_2} & \ddots & & \\ & \ddots & \ddots & \ddots & \\ & & \ddots & \frac{k_{n-1} + k_n}{m_{n-1}} & \frac{-k_n}{\sqrt{m_{n-1} m_n}} \\ & & & \frac{-k_n}{\sqrt{m_{n-1} m_n}} & \frac{k_n}{m_n} \end{bmatrix} \quad (23)$$

is real symmetric tri-diagonal matrix

$$y = M^{\frac{1}{2}} x = \begin{bmatrix} \sqrt{m_1} & & \\ & \ddots & \\ & & \sqrt{m_n} \end{bmatrix} x$$

If matrix  $A$  is known, by Algorithm 1, all the physical parameters (mass matrix  $M$  and stiffness matrix  $K$ ) can be found.

**Lemma 1**<sup>[9]</sup>: Suppose two different real numbers  $\lambda, \mu$  ( $\lambda > \mu$ ) and two nonzero vectors  $x, y$  are given. There exists a unique Jacobi matrix  $J$  with  $(\lambda, x), (\mu, y)$  as its two eigenpairs if and only if the following conditions are satisfied:

- (i)  $d_n = 0$ ;
- (ii)  $d_k / D_k > 0$  ( $k = 1, 2, \dots, n-1$ );

where

$$\begin{cases} d_k = \sum_{i=1}^k x_i y_i, (k = 1, 2, \dots, n); \\ D_k = \begin{vmatrix} x_k & x_{k+1} \\ y_k & y_{k+1} \end{vmatrix} \neq 0, (k = 1, 2, \dots, n-1); \end{cases} \quad (24)$$

And the elements of matrix  $J$  are

$$\begin{cases} b_k = (\lambda - \mu) d_k / D_k, (k = 1, 2, \dots, n-1); \\ a_1 = \lambda - b_1 x_2 / x_1, a_n = \lambda - b_{n-1} x_{n-1} / x_n; \\ a_k = \begin{cases} \lambda - (b_{k-1} x_{k-1} + b_k x_{k+1}) / x_k, x_k \neq 0; \\ \mu - (b_{k-1} y_{k-1} + b_k y_{k+1}) / y_k, x_k = 0; \end{cases} (k = 2, 3, \dots, n-1); \end{cases} \quad (25)$$

**Lemma 2**<sup>[8]</sup> Suppose three different real numbers  $\lambda, \mu, \nu$  and three nonzero vectors  $x, y, z$  are given. There exists a unique Jacobi matrix  $J$  with  $(\lambda, x), (\mu, y), (\nu, z)$  as its three eigenpairs if and only if the following conditions are satisfied:

- (i)  $d_n^{(1)} = d_n^{(2)} = d_n^{(3)} = 0$
- (ii)  $(\lambda - \mu) d_k^{(1)} / D_k^{(1)} = (\lambda - \nu) d_k^{(2)} / D_k^{(2)} > 0$ ;
- (iii) If  $x_k = 0$ ,  $(\lambda - \mu) d_j^{(1)} / D_j^{(1)} = (\mu - \nu) d_j^{(3)} / D_j^{(3)}, j = k, k-1$

where

$$\begin{cases} d_k^{(1)} = \sum_{i=1}^k x_i y_i, d_k^{(2)} = \sum_{i=1}^k x_i z_i, d_k^{(3)} = \sum_{i=1}^k y_i z_i, k = (1, 2, \dots, n); \\ D_k^{(1)} = \begin{vmatrix} y_k & y_{k+1} \\ x_k & x_{k+1} \end{vmatrix}, D_k^{(2)} = \begin{vmatrix} z_k & z_{k+1} \\ x_k & x_{k+1} \end{vmatrix}, D_k^{(3)} = \begin{vmatrix} z_k & z_{k+1} \\ y_k & y_{k+1} \end{vmatrix}, (k = 1, 2, \dots, n-1); \end{cases} \quad (26)$$

And the elements of matrix  $J$  are

$$\begin{cases} b_k = (\lambda - \mu)d_k / D_k, (k=1,2,\dots,n-1); \\ a_1 = \lambda - b_1x_2 / x_1, a_n = \lambda - b_{n-1}x_{n-1} / x_n; \\ a_k = \begin{cases} \lambda - (b_{k-1}x_{k-1} + b_kx_{k+1}) / x_k, x_k \neq 0; \\ \mu - (b_{k-1}y_{k-1} + b_ky_{k+1}) / y_k, x_k = 0; \end{cases} (k=2,3,\dots,n-1); \end{cases} \quad (27)$$

According to Lemma 1, it is shown that under some conditions the physical parameters of the mass-spring system from its two nature frequencies and corresponding modes.

#### Algorithm 2

(1) using (26) computing the  $D_i$  and  $d_i$ ;

(2) If  $d_n \neq 0$ , there is no solution to the problem;

(3) For  $k=1,2,\dots,n$ ,

If  $D_k \neq 0, (\mu - \lambda)d_k / D_k \leq 0$ , or  $D_k = 0, d_k \neq 0$ , there is no solution to the problem;

If  $D_k = 0, d_k = 0, x_k = 0$ , but  $x_{k-1}x_{k+1} \geq 0$  or  $\begin{vmatrix} x_{k-1} & x_{k+1} \\ y_{k-1} & y_{k+1} \end{vmatrix} \neq 0$ , there is no solution to the problem;

If  $D_k \neq 0$ , Computing

$$\begin{cases} b_k = (\lambda - \mu)d_k / D_k, (k=1,2,\dots,n-1); \\ a_1 = \lambda - b_1x_2 / x_1, a_n = \lambda - b_{n-1}x_{n-1} / x_n; \\ a_k = \begin{cases} \lambda - (b_{k-1}x_{k-1} + b_kx_{k+1}) / x_k, x_k \neq 0; \\ \mu - (b_{k-1}y_{k-1} + b_ky_{k+1}) / y_k, x_k = 0; \end{cases} (k=2,3,\dots,n-1); \end{cases}$$

If  $D_k = 0, d_k = 0, x_k \neq 0$ , solving the following linear equations with  $b_k > 0$

$$\begin{cases} x_k a_k + x_{k+1} b_k = \lambda x_k - x_{k-1} b_{k-1} \\ y_k a_k + y_{k+1} b_k = \mu y_k - y_{k-1} b_{k-1} \end{cases}$$

If  $D_k = 0, d_k = 0, x_k = 0$ , computing  $b_k = -x_{k-1}b_{k-1} / x_{k+1}$ ,  $a_k$  is any real number

(4) Using Algorithm1, the physical parameters of mass-spring system can be reconstructed from the computed Jacobi matrix.

Also, according to Lemma 2, we can set up the Algorithm 3 to reconstruct the physical parameters of mass-spring system from its three nature frequencies and corresponding modes. Here we can not describe any more.

## 4. Numerical Examples

Using the above theory and algorithms, we give some numerical examples here to illustrate the results obtained in this paper are correct.

**Example 1 :** Considering the mass-spring system of two degree of freedom shown in Fig.2-Fig.5.

(a) Suppose  $\lambda_1 = 1, \lambda_2 = 3, \lambda^0 = 2$  and  $m_l = 2$ , from (6) we get



$$M = \begin{bmatrix} 2 & 0 \\ 0 & \frac{1}{2} \end{bmatrix}, K = \begin{bmatrix} 4 & -1 \\ -1 & 1 \end{bmatrix}$$

So the other three physical parameters of the original mass-spring system are  $m_2 = 0.5, k_1 = 3, k_2 = 1$ .

(b) Suppose  $\lambda_1 = 2, \lambda_2 = 9, \bar{\lambda}_1 = 3, \bar{\lambda}_2 = 12$  and  $k_3 = 4$ , from (11) we get

$$M = \begin{bmatrix} \frac{169}{45} & 0 \\ 0 & 1 \end{bmatrix}, K = \begin{bmatrix} 16.9 & -6.5 \\ -6.5 & 6.5 \end{bmatrix}$$

So all the physical parameters of the original mass-spring system are  $m_1 = 3.7556, m_2 = 1, k_1 = 10.4, k_2 = 6.5$ .

(c) Suppose  $\lambda_1 = 100, \lambda_2 = 10, \bar{\lambda}_1 = 90, \bar{\lambda}_2 = 5$  and  $\Delta m = 4$ , from (14) we get

$$M = \begin{bmatrix} \frac{405}{209} & 0 \\ 0 & \frac{36}{11} \end{bmatrix}, K = \begin{bmatrix} \frac{10800}{121} + \frac{1350}{19} & -\frac{1350}{19} \\ -\frac{1350}{19} & \frac{1350}{19} \end{bmatrix}$$

So all the physical parameters of the original mass-spring system are  $m_1 = 1.9378, m_2 = 3.2727, k_1 = 71.0526, k_2 = 89.2562$ .

**Example 2 :** Considering the mass-spring of five degree of freedom shown in Fig.1.

(1) Suppose the three nature frequencies and corresponding modes of the mass-spring are given as following 432.7400, 242.2059 and mode matrix  $\varphi$  with  $m_1 = 4$ .

$$\varphi = \begin{bmatrix} -0.1638 & -0.6925 \\ 0.5224 & 0.3897 \\ -0.8232 & 0.5082 \\ 0.1428 & -0.3106 \\ -0.0260 & 0.1179 \end{bmatrix}$$

Using algorithm 2, we can reconstruct the physical parameters of the mass-spring system.

Table1 The reconstructed physical parameters

$m_1$	$m_2$	$m_3$	$m_4$	$m_5$
4	3	2	5	6
$k_1$	$k_2$	$k_3$	$k_4$	$k_5$
500	300	350	250	400

## 5. Conclusion

As a summary, we have presented some methods for reconstruction of the physical parameters of mass-spring system from its nature frequencies and corresponding modes. Numerical examples have been given to illustrate the effectiveness of our results and the proposed methods. Also, the idea in this paper may provide some insights for the physical parameters reconstruction of other vibration models by the inverse eigenvalue process, such as rods and beams and so on.

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