

# Revisiting 2PN mechanics of binary black holes

Sashwat Tanay

LUTH, Observatoire de Paris

La huitième assemblée générale du GdR Ondes Gravitationnelles  
Oct 13, 2024

In collaboration with Tom Colin, Manuel Alva Morales, Laura Bernard

# Plan of the talk

- Introduction and theory

# Plan of the talk

- Introduction and theory
- Results

# Plan of the talk

- Introduction and theory
- Results
- Summary

# Introduction and theory

# The system

- Binary black holes (BBHs) within general relativity (GR).

# The system

- Binary black holes (BBHs) within general relativity (GR).
- In inspiral state, at 2<sup>nd</sup> post-Newtonian (2PN) order;  $\frac{v^2}{c^2} \ll 1$ .

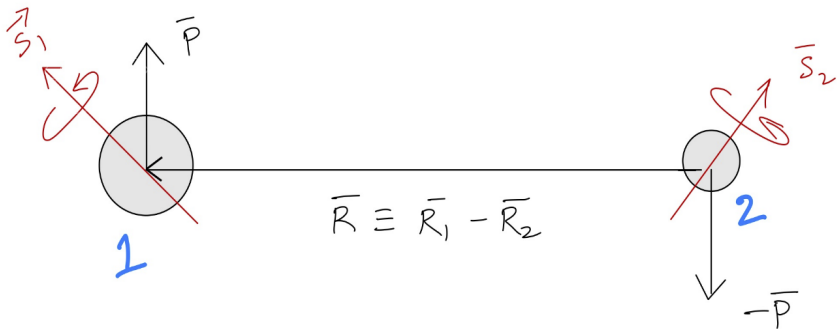
# The system

- Binary black holes (BBHs) within general relativity (GR).
- In inspiral state, at 2<sup>nd</sup> post-Newtonian (2PN) order;  $\frac{v^2}{c^2} \ll 1$ .
- Arbitrary spins and eccentricity.



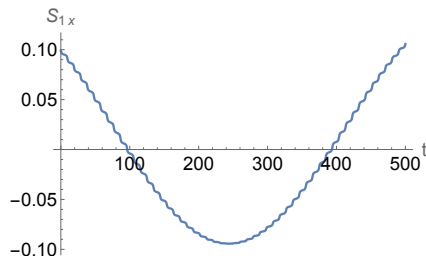
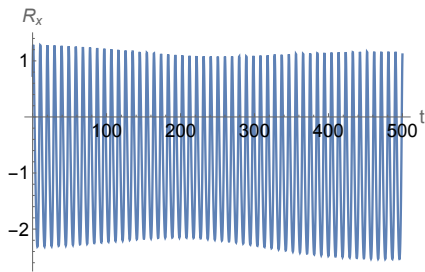
# Phase space of spinning PN BBHs

COM FRAME



$\vec{R}, \vec{P}, \vec{S}_1, \vec{S}_2$

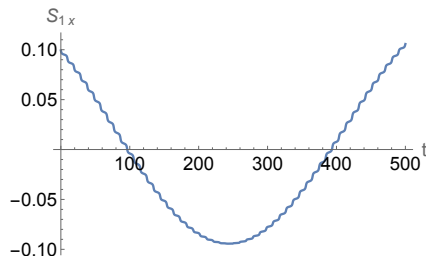
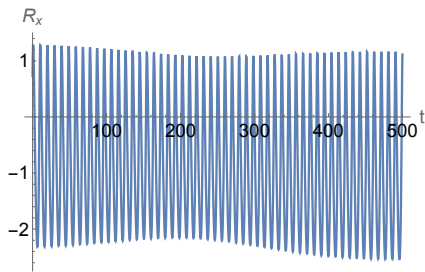
# Fast and slow variables



In the PN limit, we have

- **fast variables:**  $\vec{R}, \vec{P}$ .

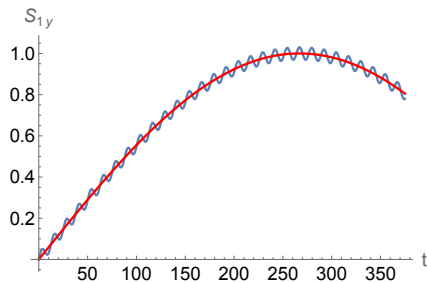
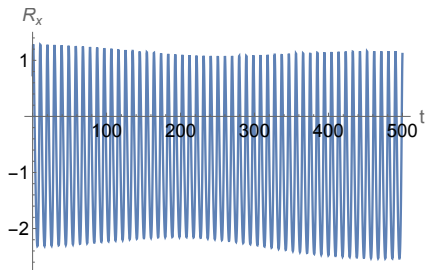
# Fast and slow variables



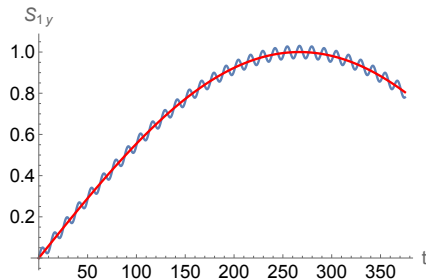
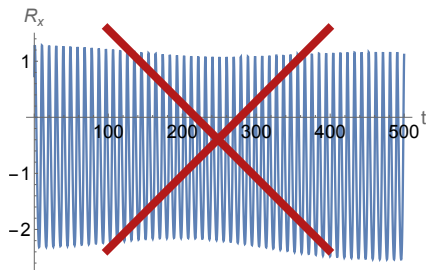
In the PN limit, we have

- **fast variables:**  $\vec{R}, \vec{P}$ .
- **slow variables:**  $\vec{S}_1, \vec{S}_2, \vec{L} \equiv \vec{R} \times \vec{P}$ .

# The “orbit-averaged” system

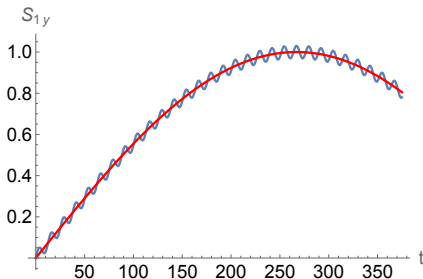
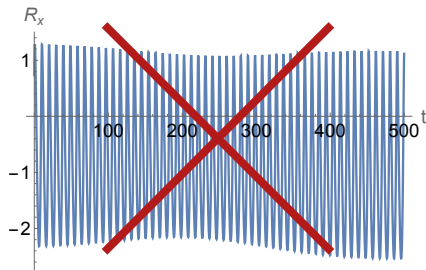


# The “orbit-averaged” system



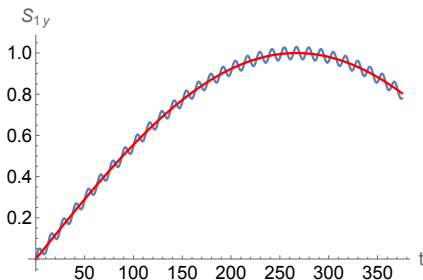
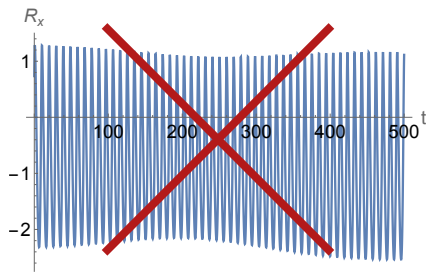
- **Fast variables** ( $\vec{R}$ ,  $\vec{P}$ ): drop them.

## The “orbit-averaged” system



- **Fast variables** ( $\vec{R}, \vec{P}$ ): drop them.
- **Slow variables** ( $\vec{S}_1, \vec{S}_2, \vec{L} \equiv \vec{R} \times \vec{P}$ ): average small perturbations over one orbit.

## The “orbit-averaged” system



- **Fast variables** ( $\vec{R}, \vec{P}$ ): drop them.
- **Slow variables** ( $\vec{S}_1, \vec{S}_2, \vec{L} \equiv \vec{R} \times \vec{P}$ ): average small perturbations over one orbit.
- **Phase space variables:**  $\vec{S}_1, \vec{S}_2, \vec{L}$ . Total number = 6 since  $\dot{S}_1 = \dot{S}_2 = \dot{L} = 0$ .

## 2PN orbit-averaged system

The equations of motion with  $M_1, M_2, M, \mu, d, \lambda$  being constants. [Racine (2008)]

$$\begin{aligned}\frac{d\mathbf{S}_1}{dt} &= \frac{1}{2d^3} \left\{ \left[ 4 + \frac{3M_2}{M_1} - \frac{3\mu}{M_1} \lambda \right] \mathbf{L} + \mathbf{S}_2 \right\} \times \mathbf{S}_1 \\ \frac{d\mathbf{S}_2}{dt} &= \frac{1}{2d^3} \left\{ \left[ 4 + \frac{3M_1}{M_2} - \frac{3\mu}{M_2} \lambda \right] \mathbf{L} + \mathbf{S}_1 \right\} \times \mathbf{S}_2 \\ \frac{d\mathbf{L}}{dt} &= \frac{1}{2d^3} \left\{ \mathbf{S} + 3 \left[ 1 - \frac{\mu}{M} \lambda \right] \mathbf{S}_0 \right\} \times \mathbf{L}\end{aligned}$$

$$\mathbf{S}_0 = \left( 1 + \frac{M_2}{M_1} \right) \mathbf{S}_1 + \left( 1 + \frac{M_1}{M_2} \right) \mathbf{S}_2.$$

$$\mathbf{S} = \mathbf{S}_1 + \mathbf{S}_2$$

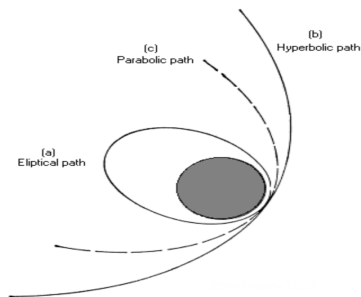


# Separatrix

Informally, a boundary separating qualitatively, two very different kinds of trajectories.

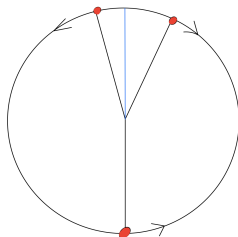
## Sun-earth system

$$H = 0.$$



## Pendulum

$$H = 2mgl.$$



[Image credit: [pages.uoregon.edu](http://pages.uoregon.edu)]

# Integrable Hamiltonian systems and action-angle variables

- **Hamiltonian system:** With  $\{q, p\} = 1$ ,  $\dot{q} = \partial H / \partial p$ ,  $\dot{p} = -\partial H / \partial q$   
 $\implies \dot{G}(q, p) = \{G, H\}$ .

# Integrable Hamiltonian systems and action-angle variables

- **Hamiltonian system:** With  $\{q, p\} = 1$ ,  $\dot{q} = \partial H / \partial p$ ,  $\dot{p} = -\partial H / \partial q$   
 $\implies \dot{G}(q, p) = \{G, H\}$ .
- **Integrable system:** canonical transformation  $(\vec{p}, \vec{q}) \leftrightarrow (\vec{\mathcal{J}}, \vec{\theta})$

# Integrable Hamiltonian systems and action-angle variables

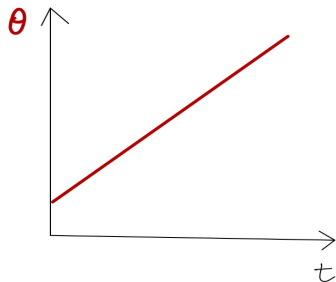
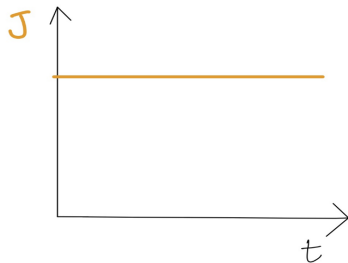
- **Hamiltonian system:** With  $\{q, p\} = 1$ ,  $\dot{q} = \partial H / \partial p$ ,  $\dot{p} = -\partial H / \partial q$   
 $\implies \dot{G}(q, p) = \{G, H\}$ .
- **Integrable system:** canonical transformation  $(\vec{p}, \vec{q}) \leftrightarrow (\vec{\mathcal{J}}, \vec{\theta})$  exists such that  $\dot{\mathcal{J}}_i = 0$ ;  $\dot{\theta}_i = \omega_i = \partial H / \partial \mathcal{J}_i$  (constant), plus other details.

# Integrable Hamiltonian systems and action-angle variables

- **Hamiltonian system:** With  $\{q, p\} = 1$ ,  $\dot{q} = \partial H / \partial p$ ,  $\dot{p} = -\partial H / \partial q$   
 $\implies \dot{G}(q, p) = \{G, H\}$ .
- **Integrable system:** canonical transformation  $(\vec{p}, \vec{q}) \leftrightarrow (\vec{\mathcal{J}}, \vec{\theta})$  exists such that  $\dot{\mathcal{J}}_i = 0$ ;  $\dot{\theta}_i = \omega_i = \partial H / \partial \mathcal{J}_i$  (constant), plus other details.
- $\mathcal{J}_i = \text{action} \sim p$ ;                       $\theta_i = \text{angle} \sim q$                       [Goldstein]

# Integrable Hamiltonian systems and action-angle variables

- **Hamiltonian system:** With  $\{q, p\} = 1$ ,  $\dot{q} = \partial H / \partial p$ ,  $\dot{p} = -\partial H / \partial q$   
 $\implies \dot{G}(q, p) = \{G, H\}$ .
- **Integrable system:** canonical transformation  $(\vec{p}, \vec{q}) \leftrightarrow (\vec{\mathcal{J}}, \vec{\theta})$  exists such that  $\dot{\mathcal{J}}_i = 0$ ;  $\dot{\theta}_i = \omega_i = \partial H / \partial \mathcal{J}_i$  (constant), plus other details.
- $\mathcal{J}_i = \text{action} \sim p$ ;  $\theta_i = \text{angle} \sim q$  [Goldstein]



# Integrable Hamiltonian systems and action-angle variables

- **Hamiltonian system:** With  $\{q, p\} = 1$ ,  $\dot{q} = \partial H / \partial p$ ,  $\dot{p} = -\partial H / \partial q$   
 $\implies \dot{G}(q, p) = \{G, H\}$ .
- **Integrable system:** canonical transformation  $(\vec{p}, \vec{q}) \leftrightarrow (\vec{\mathcal{J}}, \vec{\theta})$  exists such that  $\dot{\mathcal{J}}_i = 0$ ;  $\dot{\theta}_i = \omega_i = \partial H / \partial \mathcal{J}_i$  (constant), plus other details.
- $\mathcal{J}_i = \text{action} \sim p$ ;       $\theta_i = \text{angle} \sim q$       [Goldstein]

# Integrable Hamiltonian systems and action-angle variables

- **Hamiltonian system:** With  $\{q, p\} = 1$ ,  $\dot{q} = \partial H / \partial p$ ,  $\dot{p} = -\partial H / \partial q$   
 $\implies \dot{G}(q, p) = \{G, H\}$ .
- **Integrable system:** canonical transformation  $(\vec{p}, \vec{q}) \leftrightarrow (\vec{\mathcal{J}}, \vec{\theta})$  exists such that  $\dot{\mathcal{J}}_i = 0$ ;  $\dot{\theta}_i = \omega_i = \partial H / \partial \mathcal{J}_i$  (constant), plus other details.
- $\mathcal{J}_i = \text{action} \sim p$ ;  $\theta_i = \text{angle} \sim q$  [Goldstein]
- **Liouville-Arnold theorem:**  $2n$  phase space variables &  $n$  commuting constants of motion (i.e.  $\{C_i, C_j\} = 0$ )  $\implies$  integrability. [V. I. Arnold]



# Integrable Hamiltonian systems and action-angle variables

- **Hamiltonian system:** With  $\{q, p\} = 1$ ,  $\dot{q} = \partial H / \partial p$ ,  $\dot{p} = -\partial H / \partial q$   
 $\implies \dot{G}(q, p) = \{G, H\}$ .
- **Integrable system:** canonical transformation  $(\vec{p}, \vec{q}) \leftrightarrow (\vec{\mathcal{J}}, \vec{\theta})$  exists such that  $\dot{\mathcal{J}}_i = 0$ ;  $\dot{\theta}_i = \omega_i = \partial H / \partial \mathcal{J}_i$  (constant), plus other details.
- $\mathcal{J}_i = \text{action} \sim p$ ;  $\theta_i = \text{angle} \sim q$  [Goldstein]
- **Liouville-Arnold theorem:**  $2n$  phase space variables &  $n$  commuting constants of motion (i.e.  $\{C_i, C_j\} = 0$ )  $\implies$  integrability. [V. I. Arnold]
- 6 phase-space variables  $\implies$  3 commuting constants for integrability  $\rightarrow$  3 actions & 3 angles (3+3=6).

# Integrable Hamiltonian systems and action-angle variables

- **Hamiltonian system:** With  $\{q, p\} = 1$ ,  $\dot{q} = \partial H / \partial p$ ,  $\dot{p} = -\partial H / \partial q$   
 $\implies \dot{G}(q, p) = \{G, H\}$ .
- **Integrable system:** canonical transformation  $(\vec{p}, \vec{q}) \leftrightarrow (\vec{\mathcal{J}}, \vec{\theta})$  exists such that  $\dot{\mathcal{J}}_i = 0$ ;  $\dot{\theta}_i = \omega_i = \partial H / \partial \mathcal{J}_i$  (constant), plus other details.
- $\mathcal{J}_i = \text{action} \sim p$ ;  $\theta_i = \text{angle} \sim q$  [Goldstein]
- **Liouville-Arnold theorem:**  $2n$  phase space variables &  $n$  commuting constants of motion (i.e.  $\{C_i, C_j\} = 0$ )  $\implies$  integrability. [V. I. Arnold]
- 6 phase-space variables  $\implies$  3 commuting constants for integrability  $\rightarrow$  3 actions & 3 angles (3+3=6).
- **Line of approach:**

# Integrable Hamiltonian systems and action-angle variables

- **Hamiltonian system:** With  $\{q, p\} = 1$ ,  $\dot{q} = \partial H / \partial p$ ,  $\dot{p} = -\partial H / \partial q$   
 $\implies \dot{G}(q, p) = \{G, H\}$ .
- **Integrable system:** canonical transformation  $(\vec{p}, \vec{q}) \leftrightarrow (\vec{\mathcal{J}}, \vec{\theta})$  exists such that  $\dot{\mathcal{J}}_i = 0$ ;  $\dot{\theta}_i = \omega_i = \partial H / \partial \mathcal{J}_i$  (constant), plus other details.
- $\mathcal{J}_i = \text{action} \sim p$ ;  $\theta_i = \text{angle} \sim q$  [Goldstein]
- **Liouville-Arnold theorem:**  $2n$  phase space variables &  $n$  commuting constants of motion (i.e.  $\{C_i, C_j\} = 0$ )  $\implies$  integrability. [V. I. Arnold]
- 6 phase-space variables  $\implies$  3 commuting constants for integrability  $\rightarrow$  3 actions & 3 angles (3+3=6).
- **Line of approach:** (1) prove integrability

# Integrable Hamiltonian systems and action-angle variables

- **Hamiltonian system:** With  $\{q, p\} = 1$ ,  $\dot{q} = \partial H / \partial p$ ,  $\dot{p} = -\partial H / \partial q$   
 $\implies \dot{G}(q, p) = \{G, H\}$ .
- **Integrable system:** canonical transformation  $(\vec{p}, \vec{q}) \leftrightarrow (\vec{\mathcal{J}}, \vec{\theta})$  exists such that  $\dot{\mathcal{J}}_i = 0$ ;  $\dot{\theta}_i = \omega_i = \partial H / \partial \mathcal{J}_i$  (constant), plus other details.
- $\mathcal{J}_i = \text{action} \sim p$ ;  $\theta_i = \text{angle} \sim q$  [Goldstein]
- **Liouville-Arnold theorem:**  $2n$  phase space variables &  $n$  commuting constants of motion (i.e.  $\{C_i, C_j\} = 0$ )  $\implies$  integrability. [V. I. Arnold]
- 6 phase-space variables  $\implies$  3 commuting constants for integrability  $\rightarrow$  3 actions & 3 angles (3+3=6).
- **Line of approach:** (1) prove integrability (2) find action-angles

## Integrable systems are nice (and rare) systems!

- Integrability  $\implies$  no chaos. Chaos  $\implies$  analytical and numerical solutions numerical become elusive.

## Integrable systems are nice (and rare) systems!

- Integrability  $\implies$  no chaos. Chaos  $\implies$  analytical and numerical solutions numerical become elusive.
- Action-angles  $\rightarrow$  solution and frequencies.

## Integrable systems are nice (and rare) systems!

- Integrability  $\implies$  no chaos. Chaos  $\implies$  analytical and numerical solutions numerical become elusive.
- Action-angles  $\rightarrow$  solution and frequencies.
- Action-angles  $\rightarrow$  resonances ( $\omega_i/\omega_j = n_1/n_2$ ) and separatrices via  $\det \left( \frac{\partial \vec{C}}{\partial \vec{J}} \right) = 0$ .

## Integrable systems are nice (and rare) systems!

- Integrability  $\implies$  no chaos. Chaos  $\implies$  analytical and numerical solutions numerical become elusive.
- Action-angles  $\rightarrow$  solution and frequencies.
- Action-angles  $\rightarrow$  resonances ( $\omega_i/\omega_j = n_1/n_2$ ) and separatrices via  $\det \left( \frac{\partial \vec{C}}{\partial \vec{J}} \right) = 0$ .
- Canonical perturbation theory & Lie transformation:  
 $(\vec{J}_{\text{old}}, \vec{\theta}_{\text{old}}, \vec{\omega}_{\text{old}}) \rightarrow (\vec{J}_{\text{new}}, \vec{\theta}_{\text{new}}, \vec{\omega}_{\text{new}})$ . [Goldstein]



## Integrable systems are nice (and rare) systems!

- Integrability  $\implies$  no chaos. Chaos  $\implies$  analytical and numerical solutions numerical become elusive.
- Action-angles  $\rightarrow$  solution and frequencies.
- Action-angles  $\rightarrow$  resonances ( $\omega_i/\omega_j = n_1/n_2$ ) and separatrices via  $\det \left( \frac{\partial \vec{C}}{\partial \vec{J}} \right) = 0$ .
- Canonical perturbation theory & Lie transformation:  
 $(\vec{J}_{\text{old}}, \vec{\theta}_{\text{old}}, \vec{\omega}_{\text{old}}) \rightarrow (\vec{J}_{\text{new}}, \vec{\theta}_{\text{new}}, \vec{\omega}_{\text{new}})$ . [Goldstein]

It's nice to have integrable systems (they occur rarely),

## Integrable systems are nice (and rare) systems!

- Integrability  $\implies$  no chaos. Chaos  $\implies$  analytical and numerical solutions numerical become elusive.
- Action-angles  $\rightarrow$  solution and frequencies.
- Action-angles  $\rightarrow$  resonances ( $\omega_i/\omega_j = n_1/n_2$ ) and separatrices via  $\det \left( \frac{\partial \vec{C}}{\partial \vec{J}} \right) = 0$ .
- Canonical perturbation theory & Lie transformation:  
 $(\vec{J}_{\text{old}}, \vec{\theta}_{\text{old}}, \vec{\omega}_{\text{old}}) \rightarrow (\vec{J}_{\text{new}}, \vec{\theta}_{\text{new}}, \vec{\omega}_{\text{new}})$ . [Goldstein]

It's nice to have integrable systems (they occur rarely), and extra nice to have action-angle variables.

# Results

## Results: Hamiltonian system

$$\begin{aligned}\frac{d\mathbf{S}_1}{dt} &= \frac{1}{2d^3} \left\{ \left[ 4 + \frac{3M_2}{M_1} - \frac{3\mu}{M_1} \lambda \right] \mathbf{L} + \mathbf{S}_2 \right\} \times \mathbf{S}_1 \\ \frac{d\mathbf{S}_2}{dt} &= \frac{1}{2d^3} \left\{ \left[ 4 + \frac{3M_1}{M_2} - \frac{3\mu}{M_2} \lambda \right] \mathbf{L} + \mathbf{S}_1 \right\} \times \mathbf{S}_2 \\ \frac{d\mathbf{L}}{dt} &= \frac{1}{2d^3} \left\{ \mathbf{S} + 3 \left[ 1 - \frac{\mu}{M} \lambda \right] \mathbf{S}_0 \right\} \times \mathbf{L}\end{aligned}$$

## Results: Hamiltonian system

$$\begin{aligned}\frac{d\mathbf{S}_1}{dt} &= \frac{1}{2d^3} \left\{ \left[ 4 + \frac{3M_2}{M_1} - \frac{3\mu}{M_1} \lambda \right] \mathbf{L} + \mathbf{S}_2 \right\} \times \mathbf{S}_1 \\ \frac{d\mathbf{S}_2}{dt} &= \frac{1}{2d^3} \left\{ \left[ 4 + \frac{3M_1}{M_2} - \frac{3\mu}{M_2} \lambda \right] \mathbf{L} + \mathbf{S}_1 \right\} \times \mathbf{S}_2 \\ \frac{d\mathbf{L}}{dt} &= \frac{1}{2d^3} \left\{ \mathbf{S} + 3 \left[ 1 - \frac{\mu}{M} \lambda \right] \mathbf{S}_0 \right\} \times \mathbf{L}\end{aligned}$$

This is a Hamiltonian system with the Hamiltonian

$$\begin{aligned}H &= \frac{1}{4d^3 m_1 m_2 L^2} \left\{ -3 \left( m_2 \vec{L} \cdot \vec{S}_1 + (1 \leftrightarrow 2) \right)^2 \right. \\ &\quad \left. + 2L^2 \left( m_2 (4m_1 + 3m_2) \vec{L} \cdot \vec{S}_1 + \frac{1}{2} m_1 m_2 \vec{S}_1 \cdot \vec{S}_2 + (1 \leftrightarrow 2) \right) \right\} \quad (1)\end{aligned}$$

## Results: integrability and action-angle variables

- 3 constants of motion already known  $\implies$  integrability.

## Results: integrability and action-angle variables

- 3 constants of motion already known  $\implies$  integrability.
- We construct all 3 actions & angle variables.

## Results: integrability and action-angle variables

- 3 constants of motion already known  $\implies$  integrability.
- We construct all 3 actions & angle variables.
- We construct  $(\vec{S}_1, \vec{S}_2, \vec{L})$  as functions of  $(\vec{J}, \vec{\theta})$ ,



## Results: integrability and action-angle variables

- 3 constants of motion already known  $\implies$  integrability.
- We construct all 3 actions & angle variables.
- We construct  $(\vec{S}_1, \vec{S}_2, \vec{L})$  as functions of  $(\vec{J}, \vec{\theta})$ , thereby constructing the solution  $(\vec{S}_1(t), \vec{S}_2(t), \vec{L}(t))$ .

## Results: integrability and action-angle variables

- 3 constants of motion already known  $\implies$  integrability.
- We construct all 3 actions & angle variables.
- We construct  $(\vec{S}_1, \vec{S}_2, \vec{L})$  as functions of  $(\vec{J}, \vec{\theta})$ , thereby constructing the solution  $(\vec{S}_1(t), \vec{S}_2(t), \vec{L}(t))$ .
- Matches with the numerical and the already-existing non-AA-based analytical solutions [Kesden & others - 2014]

## Results: action expressions

- $\sigma_1 \equiv (1 + m_2/m_1), \quad \sigma_2 \equiv (1 + m_1/m_2),$   
 $\vec{L} \equiv \vec{R} \times \vec{P}, \quad \vec{S}_{\text{eff}} \equiv \sigma_1 \vec{S}_1 + \sigma_2 \vec{S}_2,$   
 $\vec{J} = \vec{L} + \vec{S}_1 + \vec{S}_2, \quad \mathcal{C}_1 = J^2 - L^2 - S_1^2 - S_2^2$   
 $\mathcal{C}_2 = \left[ 1 - \frac{4(\mathcal{C}_1 \sigma_1 - 2\mathbf{S}_{\text{eff}} \cdot \mathbf{L})(\mathcal{C}_1 \sigma_2 - 2\mathbf{S}_{\text{eff}} \cdot \mathbf{L})}{(\mathcal{C}_1(\sigma_1 + \sigma_2) - 4\mathbf{S}_{\text{eff}} \cdot \mathbf{L})^2 - 4L^2(\sigma_1 - \sigma_2)^2(S_1^2 + S_2^2)} \right]^{1/2} - 1$

## Results: action expressions

- $\sigma_1 \equiv (1 + m_2/m_1), \quad \sigma_2 \equiv (1 + m_1/m_2),$   
 $\vec{L} \equiv \vec{R} \times \vec{P}, \quad \vec{S}_{\text{eff}} \equiv \sigma_1 \vec{S}_1 + \sigma_2 \vec{S}_2,$   
 $\vec{J} = \vec{L} + \vec{S}_1 + \vec{S}_2, \quad \mathcal{C}_1 = J^2 - L^2 - S_1^2 - S_2^2$   
 $\mathcal{C}_2 = \left[ 1 - \frac{4(\mathcal{C}_1 \sigma_1 - 2\mathbf{S}_{\text{eff}} \cdot \mathbf{L})(\mathcal{C}_1 \sigma_2 - 2\mathbf{S}_{\text{eff}} \cdot \mathbf{L})}{(\mathcal{C}_1(\sigma_1 + \sigma_2) - 4\mathbf{S}_{\text{eff}} \cdot \mathbf{L})^2 - 4L^2(\sigma_1 - \sigma_2)^2(S_1^2 + S_2^2)} \right]^{1/2} - 1$
- $\mathcal{J}_1 = J, \quad \mathcal{J}_2 = J_z.$

## Results: action expressions

- $$\sigma_1 \equiv (1 + m_2/m_1), \quad \sigma_2 \equiv (1 + m_1/m_2),$$

$$\vec{L} \equiv \vec{R} \times \vec{P}, \quad \vec{S}_{\text{eff}} \equiv \sigma_1 \vec{S}_1 + \sigma_2 \vec{S}_2,$$

$$\vec{J} = \vec{L} + \vec{S}_1 + \vec{S}_2, \quad C_1 = J^2 - L^2 - S_1^2 - S_2^2$$

$$C_2 = \left[ 1 - \frac{4(C_1\sigma_1 - 2S_{\text{eff}} \cdot L)(C_1\sigma_2 - 2S_{\text{eff}} \cdot L)}{(C_1(\sigma_1 + \sigma_2) - 4S_{\text{eff}} \cdot L)^2 - 4L^2(\sigma_1 - \sigma_2)^2(S_1^2 + S_2^2)} \right]^{1/2} - 1$$

- $$\mathcal{J}_1 = J, \quad \mathcal{J}_2 = J_z.$$

- Third action

$$\mathcal{J}_3 = \frac{1}{4\mathcal{L}(\sigma_1 - \sigma_2)(C_1^2 - 4\mathcal{L}^2(S_1^2 + S_2^2))} [C_1^3 C_2(\sigma_1 + \sigma_2) + 4C_1 \mathcal{L}^2 \{S_1^2(C_2(\sigma_1 - \sigma_2) + 2\sigma_1)$$

$$+ S_2^2(C_2(\sigma_2 - \sigma_1) + 2\sigma_2)\} - (S_{\text{eff}} \cdot L) \{16L^2(S_1^2 + S_2^2) + 4C_1^2 C_2\}]$$

## Results: resonances and separatrices

- Rediscover the already-found resonances by  $\omega_1/\omega_2 = n_1/n_2$ , where  $\omega_i = \partial H/\partial \mathcal{J}_i$ , plus potentially more.

## Results: resonances and separatrices

- Rediscover the already-found resonances by  $\omega_1/\omega_2 = n_1/n_2$ , where  $\omega_i = \partial H/\partial \mathcal{J}_i$ , plus potentially more.
- Separatrix criterion  $\det \left( \frac{\partial \vec{C}}{\partial \vec{J}} \right) = 0$  gives only the already-known elliptic  $\leftrightarrow$  hyperbolic separatrix.

## Results: resonances and separatrices

- Rediscover the already-found resonances by  $\omega_1/\omega_2 = n_1/n_2$ , where  $\omega_i = \partial H/\partial \mathcal{J}_i$ , plus potentially more.
- Separatrix criterion  $\det \left( \frac{\partial \vec{C}}{\partial \vec{J}} \right) = 0$  gives only the already-known elliptic  $\leftrightarrow$  hyperbolic separatrix. Hence no new separatrix from the spin DOFs.



# Summary

# Summary

## 2PN orbit-averaged, eccentric and spinning BBH

# Summary

## **2PN orbit-averaged, eccentric and spinning BBH**

- We show it is Hamiltonian by discovering its Hamiltonian.

# Summary

## **2PN orbit-averaged, eccentric and spinning BBH**

- We show it is Hamiltonian by discovering its Hamiltonian.
- Integrability follows from the already-known constants of motion

# Summary

## **2PN orbit-averaged, eccentric and spinning BBH**

- We show it is Hamiltonian by discovering its Hamiltonian.
- Integrability follows from the already-known constants of motion
- Action-angle variables and solution constructed.

# Summary

## 2PN orbit-averaged, eccentric and spinning BBH

- We show it is Hamiltonian by discovering its Hamiltonian.
- Integrability follows from the already-known constants of motion
- Action-angle variables and solution constructed.
- Action-angle variables  $\rightarrow$  frequencies  $\rightarrow$  already-known resonances recovered.

# Summary

## 2PN orbit-averaged, eccentric and spinning BBH

- We show it is Hamiltonian by discovering its Hamiltonian.
- Integrability follows from the already-known constants of motion
- Action-angle variables and solution constructed.
- Action-angle variables  $\rightarrow$  frequencies  $\rightarrow$  already-known resonances recovered.
- The spin degrees don't give rise to any new separatrix. Only elliptic  $\leftrightarrow$  hyperbolic separatrix known so far.

# Summary

## 2PN orbit-averaged, eccentric and spinning BBH

- We show it is Hamiltonian by discovering its Hamiltonian.
- Integrability follows from the already-known constants of motion
- Action-angle variables and solution constructed.
- Action-angle variables  $\rightarrow$  frequencies  $\rightarrow$  already-known resonances recovered.
- The spin degrees don't give rise to any new separatrix. Only elliptic  $\leftrightarrow$  hyperbolic separatrix known so far.

**Ongoing:** Construct solutions for full (w/o orbit-averaging) 2PN spinning, eccentric systems.