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
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of the system. The first two terms in the above equation represent the forces due to the mass and stiffness of the system, respectively. The third term represents the force due to the damping of the system. The fourth term represents the force due to the external excitation of the system. The fifth term represents the force due to the interaction of the system with the surrounding environment.

The above equation can be rearranged to give the following form:

$$m\ddot{x} + c\dot{x} + kx = F\cos(\omega t) + \dots$$

where  $m$  is the mass of the system,  $c$  is the damping coefficient,  $k$  is the stiffness of the system,  $F$  is the amplitude of the external excitation,  $\omega$  is the angular frequency of the external excitation, and  $\dots$  represents the force due to the interaction of the system with the surrounding environment.

The above equation is a second-order differential equation. It can be solved using a variety of methods, including analytical methods and numerical methods. The analytical methods are typically used for simple systems, while the numerical methods are used for more complex systems.

The numerical methods are typically used for systems that are too complex to solve analytically. The numerical methods involve discretizing the time domain and solving the resulting system of equations using a computer.

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