

2/175  $\theta = \omega t = \frac{20}{180} \pi = 0.698 \text{ rad/s}$   
 $\dot{\theta} = \frac{20}{180} \pi = 0.1745 \text{ rad/s}$   
 $\ddot{\theta} = \frac{20}{180} \pi = 0.149 \text{ rad/s}^2$   
 Use cylindrical coordinates  
 $r = b \cos \beta + c \sin \beta$ ,  $\dot{r} = (-b \sin \beta + c \cos \beta) \dot{\beta}$   
 $\ddot{r} = (-b \cos \beta - c \sin \beta) \dot{\beta}^2 + (-b \sin \beta + c \cos \beta) \ddot{\beta}$   
 $\theta = b + c \sin \beta + c \cos \beta$ ,  $\dot{\theta} = (-b \sin \beta + c \cos \beta) \dot{\beta}$   
 $\ddot{\theta} = (-b \cos \beta - c \sin \beta) \dot{\beta}^2 + (-b \sin \beta + c \cos \beta) \ddot{\beta}$   
 For  $\beta = 90^\circ$ ,  $\dot{r} = (-300 + 0.5 + 200 + 0.956)(0.1745) = 4.050 \text{ mm/s}$   
 $\ddot{r} = (-300 + 0.5 - 200 + 0.9)(0.1745)^2 + (-300 + 0.5 + 200 + 0.956)(0.149) = -2.865 \text{ mm/s}^2$   
 $\dot{\theta} = (-300 + 0.5 + 200 + 0.956)(0.1745) = 126.30 \text{ mm/s}$   
 $\ddot{\theta} = (-300 + 0.5 - 200 + 0.9)(0.1745)^2 + (-300 + 0.5 + 200 + 0.956)(0.149) = 5.65 \text{ mm/s}^2$   
 $a_r = \ddot{r} - r\dot{\theta}^2 = -2.865 - 126.30^2(0.1745)^2 = -2.89 \text{ mm/s}^2$   
 $a_\theta = r\ddot{\theta} + 2\dot{r}\dot{\theta} = 0 + 2(4.050)(0.1745) = 1.413 \text{ mm/s}^2$

2/176  $a_r = \ddot{r} - r\dot{\theta}^2 = 0 - r\omega^2$   
 $a_\theta = r\ddot{\theta} + 2\dot{r}\dot{\theta} = 0 + 0 = 0$   
 $a_s = \frac{d}{dt}(L \sin \omega t) = -L\omega^2 \sin 2\omega t$   
 $a = \sqrt{(-r\omega^2)^2 + (-L\omega^2 \sin 2\omega t)^2}$   
 $a_{\max} = \sqrt{r^2\omega^2 + L^2\omega^2} = 2.19 \text{ m/s}^2$

2/177 Helix angle is  $\gamma = \tan^{-1} \frac{10}{24} = 22.5^\circ$   
 $v = 15 \left( \frac{5280}{3600} \right) = 22 \text{ ft/sec}$   
 $v_x = v \sin \gamma = 22 \sin 22.5^\circ = 8.47 \text{ ft/sec}$   
 $v_y = v \cos \gamma = 22 \cos 22.5^\circ = 20.2 \text{ ft/sec}$   
 From  $v_y = r\dot{\theta}$ ,  $\dot{\theta} = \frac{20.2}{24} = 0.842 \text{ rad/sec}$   
 $a_{x2} = 2 \left( \frac{5280}{3600} \right) = 2.93 \text{ ft/sec}^2$   
 $a_y = -2.93 \cos 22.5^\circ = -2.71 \text{ ft/sec}^2$   
 $a_z = -2.93 \sin 22.5^\circ = -0.56 \text{ ft/sec}^2$   
 $a_r = \ddot{r} - r\dot{\theta}^2 = 0 - 24(0.842)^2 = -17.82 \text{ ft/sec}^2$

2/178  $\beta = \tan^{-1} \frac{1}{2} = 26.6^\circ$   
 $\phi = \tan^{-1} \frac{3}{4} = 36.9^\circ$   
 $v_R = 400 \sin 26.6^\circ \sin 36.9^\circ = 92.0 \text{ km/h} = R$   
 $\omega = 0.1788 \text{ rad/s}$   
 $\dot{\phi} = 0.0731 \text{ rad/s}$

2/179  $v_r = \dot{r} \sin \beta = c \sin \beta$   
 $v_\theta = r\dot{\theta} = (L \sin \beta)K = KL \sin \beta$   
 $v_s = \dot{s} \cos \beta = c \cos \beta$   
 $\dot{s} = K \sqrt{(c \sin \beta)^2 + (KL \sin \beta)^2 + (c \cos \beta)^2}$   
 $= \sqrt{c^2 + K^2 L^2 \sin^2 \beta}$   
 $a_r = \ddot{r} - r\dot{\theta}^2 = 0 - L \sin \beta (K^2) = -K^2 L \sin \beta$   
 $a_\theta = r\ddot{\theta} + 2\dot{r}\dot{\theta} = 0 + 2c \sin \beta (K) = 2Kc \sin \beta$   
 $a_s = \dot{v}_s = 0$   
 $a = \sqrt{(-K^2 L \sin \beta)^2 + (2Kc \sin \beta)^2} = K \sin \beta \sqrt{K^2 L^2 + 4c^2}$

2/180  $\theta = \omega t = \frac{\pi}{2} t$   
 $\dot{\theta} = \frac{\pi}{2}$   
 $\begin{cases} x' = r \cos \theta \\ y' = r \sin \theta \\ z' = 0 \end{cases}$   
 $\begin{cases} \dot{x}' = -r\dot{\theta} \sin \theta \\ \dot{y}' = r\dot{\theta} \cos \theta \\ \dot{z}' = 0 \end{cases}$   
 $\ddot{x}' = -r\dot{\theta}^2 \cos \theta, \ddot{y}' = -r\dot{\theta}^2 \sin \theta, \ddot{z}' = 0$   
 Component relationship:  
 $\begin{cases} x = x' \cos 30^\circ + z' \sin 30^\circ \\ y = y' \\ z = -x' \sin 30^\circ + z' \cos 30^\circ \end{cases}$   
 Thus  $\frac{dx}{dt} = \frac{1}{2} r \cos \frac{\pi}{2} t, \frac{dy}{dt} = r \sin \frac{\pi}{2} t, \frac{dz}{dt} = -\frac{1}{2} r \cos \frac{\pi}{2} t$   
 $\ddot{x} = -\frac{1}{2} \dot{r} \sin \frac{\pi}{2} t, \ddot{y} = \dot{r} \cos \frac{\pi}{2} t, \ddot{z} = \frac{1}{2} \dot{r} \sin \frac{\pi}{2} t$   
 $\ddot{x} = -\frac{1}{2} \frac{dy}{dt}, \ddot{y} = \frac{dx}{dt}, \ddot{z} = \frac{1}{2} \frac{dy}{dt}$   
 Note that position relationships do not include the constants associated with the origin position.

2/181  $a = \frac{v^2}{r}$   
 $v = 600 \text{ km/h}$   
 $\phi = \tan^{-1} \frac{400}{1000} = 21.8^\circ$   
 $a = \frac{v^2}{r} = \frac{(600/3.6)^2}{1200} = 23.1 \text{ m/s}^2$   
 $R = 0, \dot{\theta} = 0, \ddot{\theta} = \frac{v_R}{R \cos \beta} = \frac{600(1000)/3.6}{1000} = 0.1667 \text{ s}^{-2}$   
 Eqs. 2/19:  $a_R = \ddot{R} - R\dot{\theta}^2 - R\dot{\phi}^2 \cos^2 \beta$   
 $23.1 \sin 21.8^\circ = \ddot{R} - 0 - \frac{1000}{\cos 21.8^\circ} (0.1667)^2 \cos^2 21.8^\circ$   
 $\ddot{R} = 34.4 \text{ m/s}^2$   
 $a_\phi = \frac{1}{R} \frac{d}{dt} (R^2 \dot{\phi}) + R \dot{\theta}^2 \sin \beta \cos \beta = 2\dot{\theta} \dot{\phi} + R \dot{\theta}^2 \sin \beta \cos \beta$   
 $23.1 \cos 21.8^\circ = 0 + \frac{1000}{\cos 21.8^\circ} \dot{\phi} + \frac{1000}{\cos 21.8^\circ} 0.1667^2 \sin 21.8^\circ \cos 21.8^\circ$   
 $\dot{\phi} = 0.01038 \text{ rad/s}^2$

# Meriam Dynamics 6th Edition Solution

**S Ashworth**



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Robots Mechanics and Control presents a systematic approach to analyze the kinematics dynamics and control of parallel robots It brings together analysis and design tools for engineers and researchers who want to design and implement parallel structures in industry Covers Kinematics Dynamics and Control in One Volume The book begins with the representation of motion of robots and the kinematic analysis of parallel manipulators Moving beyond static positioning it then examines a systematic approach to performing Jacobian analysis A special feature of the book is its detailed coverage of the dynamics and control of parallel manipulators The text examines dynamic analysis using the Newton Euler method the principle of virtual work and the Lagrange formulations Finally the book elaborates on the control of parallel robots considering both motion and force control It introduces various model free and model based controllers and develops robust and adaptive control schemes It also addresses redundancy resolution schemes in detail Analysis and Design Tools to Help You Create Parallel Robots In each chapter the author revisits the same case studies to show how the techniques may be applied The case studies include a planar cable driven parallel robot part of a promising new generation of parallel structures that will allow for larger workspaces The MATLAB code used for analysis and simulation is available online Combining the analysis of kinematics and dynamics with methods of designing controllers this text offers a holistic introduction for anyone interested in designing and implementing parallel robots

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