

1/1

$$a) m = \frac{W}{g} = \frac{3600}{32.2} = 111.8 \text{ slugs}$$

$$b) W = 3600 \text{ lb} \left[\frac{4.4482 \text{ N}}{\text{lb}} \right] = 16,014 \text{ N}$$

$$c) m = \frac{W}{g} = \frac{16,014}{9.81} = 1632 \text{ kg}$$

$$\left(\text{or } m = 111.8 \text{ slugs} \left[\frac{14.594 \text{ kg}}{\text{slug}} \right] = 1632 \text{ kg} \right)$$

1/2

For a 180-lb person:

$$W = mg : 180 \text{ lb} = m (32.2 \text{ ft/sec}^2)$$

$$180 \text{ lb} \left(\frac{4.4482 \text{ N}}{\text{lb}} \right) = 801 \text{ N}$$

$$W = mg : 801 \text{ N} = m (9.81 \text{ m/s}^2)$$

$$m = 81.6 \text{ kg}$$

1/3

$$\underline{V_1} = 15 \left(\frac{4}{5} \underline{i} + \frac{3}{5} \underline{j} \right) = 12 \underline{i} + 9 \underline{j}$$

$$\underline{V_2} = 12 (-\cos 60^\circ \underline{i} + \sin 60^\circ \underline{j}) = -6 \underline{i} + 10.39 \underline{j}$$

$$\underline{V_1} + \underline{V_2} = 15 + 12 = 27$$

$$\underline{V_1} + \underline{V_2} = (12-6) \underline{i} + (9+10.39) \underline{j} = 6 \underline{i} + 19.39 \underline{j}$$

$$\underline{V_1} - \underline{V_2} = (12-(-6)) \underline{i} + (9-10.39) \underline{j} = 18 \underline{i} - 1.39 \underline{j}$$

$$\underline{V_1} \times \underline{V_2} = (12 \underline{i} + 9 \underline{j}) \times (-6 \underline{i} + 10.39 \underline{j})$$

$$= (24.7 + 54) \underline{k} = 178.7 \underline{k}$$

$$\underline{V_2} \times \underline{V_1} = -(\underline{V_1} \times \underline{V_2}) = -178.7 \underline{k}$$

$$\underline{V_1} \cdot \underline{V_2} = (12 \underline{i} + 9 \underline{j}) \cdot (-6 \underline{i} + 10.39 \underline{j})$$

$$= 12(-6) + 9(10.39) = 21.5$$

1/4

The weight of an average apple is

$$W = \frac{5 \text{ lb}}{12 \text{ apples}} = 0.417 \text{ lb}$$

$$\text{Mass in slugs is } m = \frac{W}{g} = \frac{0.417}{32.2} = 0.01294 \text{ slugs}$$

$$\text{Mass in kg is } m = 0.01294 \text{ slugs} \left(\frac{14.594 \text{ kg}}{1 \text{ slug}} \right) = 0.1888 \text{ kg}$$

$$\text{Weight in N is } W = mg = 0.1888 (9.81) = 1.853 \text{ N}$$

These apples weigh closer to 2 N each than to the rule of 1 N each!

1/5

Mass of iron sphere $m = \rho V$

$$= (7210 \frac{\text{kg}}{\text{m}^3}) \left(\frac{4}{3} \pi (0.050)^3 \right) = 3.78 \text{ kg}$$

Force of mutual attraction: $\frac{Gm^2}{d^2}$ Weight of each sphere: $\frac{Gm_e m}{r^2}$

$$\frac{Gm^2}{d^2} = \frac{Gm_e m}{r^2}, \quad r = d \sqrt{\frac{m_e}{m}}$$

$$= 0.1 \sqrt{\frac{5.97 \times 10^{24}}{3.78}} \frac{1}{10^3}$$

$$= 1.258 (10^3) \text{ km}$$

1/6



$r = 0.050 \text{ m}$ for all spheres

$$\underline{F_B} = \frac{Gm_B m_A}{d_{AB}^2} = \frac{G \left(f_A \frac{4}{3} \pi r^3 \right) \left(f_B \frac{4}{3} \pi r^3 \right)}{d_{AB}^2}$$

$$= \frac{6.673 (10^{-11}) \left[\frac{4}{3} \pi (0.050)^3 \right]^2 (8910)(2670)}{1^2}$$

$$= 4.38 (10^{-10}) \text{ N}$$

$$\underline{F_C} = \frac{Gm_B m_C}{d_{BC}^2} = \frac{G \left[\frac{4}{3} \pi r^3 \right]^2 f_B f_C}{d_{BC}^2}$$

$$= \frac{6.673 (10^{-11}) \left[\frac{4}{3} \pi (0.050)^3 \right]^2 (8910)(7210)}{1^2}$$

$$= 1.175 (10^{-9}) \text{ N}$$

$$\underline{R} = \underline{F_B} + \underline{F_C} = 4.38 (10^{-10}) [-\sin 30^\circ \underline{i} + \cos 30^\circ \underline{j}]$$

$$+ 1.175 (10^{-9}) [\sin 30^\circ \underline{i} + \cos 30^\circ \underline{j}]$$

$$\underline{R} = (3.68 \underline{i} - 13.98 \underline{j}) 10^{-10} \text{ N}$$

1/7

$$\Delta t = \frac{Gm_e}{(R+h)^2}$$

$$= \frac{(3.439 \times 10^{-8}) (4.075 \times 10^{22})}{[(3959)(5280) + (150)(5280)]^2} = 2.99 \text{ 1/sec}^2$$

$$\text{Mass of man: } m = \frac{W}{g} = \frac{200}{32.174} = 6.22 \text{ slugs}$$

Absolute weight at $h = 150$ miles:

$$W_h = mg_h = (6.22)(29.9) = 186.0 \text{ lb}$$

The terms "zero-g" and "weightless" are definitely misnomers in this instance.

1/8

$$mg = 0.1 mg_0$$

$$\frac{R}{(R+h)^2} g_0 = 0.1 g_0$$

$$\text{Solve for } h \text{ to obtain } h = 2.16R$$

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Bingen Yang



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Essential Mechanics - Statics and Strength of Materials with MATLAB and Octave P. Venkataraman,2020-01-07 Essential Mechanics Statics and Strength of Materials with MATLAB and Octave combines two core engineering science courses Statics and Strength of Materials in mechanical civil and aerospace engineering It weaves together various essential

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Essentials of Dynamics and Vibrations John Billingsley, 2025-03-02 This updated second edition brings the complex mathematics of three dimensional dynamics to life with real time simulations making the equations easier to grasp Covering core topics in mechanical engineering such as kinematics dynamics vibration analysis gyroscopes gears and Euler s equations the book offers a clear and engaging approach for students professionals and enthusiasts alike With a focus on practical applications it explains everything from the laws of motion to motors and mechanisms providing a comprehensive understanding of mechanical systems New to this edition is a chapter on Power Energy and Perpetual Motion which reveals intriguing comparisons such as the energy needed to lift water versus the heat required to warm it The final chapter Rocket Science has been expanded to debunk myths about black holes and gravity humorously addressing science fiction misconceptions while proposing exciting space projects *Solving Dynamics Problems in MathCad A Supplement to Accompany Engineering Mechanics: Dynamics, 5th Edition by Meriam & Kraige* Brian Harper, 2001-11-26 If MathCad is the computer algebra system you need to use for your engineering calculations and graphical output Harper s Solving Dynamics Problems in MathCad is the reference that will be a valuable tutorial for your studies Written as a guidebook for students taking the Engineering Mechanics course it will help you with your engineering assignments throughout the course Over the past 50 years Meriam Kraige s Engineering Mechanics Dynamics has established a highly respected tradition of Excellence A Tradition that emphasizes accuracy rigor clarity and applications Now completely revised redesigned and modernized the new fifth edition of this classic text builds on these strengths adding new problems and a more accessible student friendly presentation **Mechanical Vibrations** György Szeidl, László Péter Kiss, 2020-06-16 This book presents a unified introduction to the theory of mechanical vibrations The general theory of the vibrating particle is the point of departure for the field of multidegree of freedom systems Emphasis is placed in the text on the issue of continuum vibrations The presented examples are aimed at helping the readers with understanding the theory This book is of interest among others to

mechanical civil and aeronautical engineers concerned with the vibratory behavior of the structures It is useful also for students from undergraduate to postgraduate level The book is based on the teaching experience of the authors *Parallel Robots* Hamid D. Taghirad, 2013-02-20 Parallel structures are more effective than serial ones for industrial automation applications that require high precision and stiffness or a high load capacity relative to robot weight Although many industrial applications have adopted parallel structures for their design few textbooks introduce the analysis of such robots in terms of dynamics and control Filling this gap *Parallel 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 **Books in Print**

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