

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 $v_y = r\dot{\theta}$, $\dot{\theta} = \frac{20.2}{24} = 0.842 \text{ rad/sec}$
 $a_{sz} = 2 \left(\frac{5280}{3600} \right) = 2.93 \text{ ft/sec}^2$
 $a_y = -2.93 \cos 22.5^\circ = -2.71 \text{ ft/sec}^2$
 $a_x = -2.93 \sin 22.5^\circ = -0.56 \text{ ft/sec}^2$
 $a_r = \ddot{r} - r\dot{\theta}^2 = 0 - 24(0.842)^2 = -17.82 \text{ ft/sec}^2$

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:
 $\begin{cases} x = x' \cos 30^\circ + x'' \sin 30^\circ \\ y = y' \end{cases}$
 (Similar for $\ddot{x}, \ddot{y}$, etc.)
 Thus $\ddot{x} = \ddot{x}' \cos 30^\circ + \ddot{x}'' \sin 30^\circ$
 $\ddot{x} = -\frac{\sqrt{3}}{2} r \dot{\theta}^2 \cos \frac{\pi}{2} t, \ddot{y} = r \dot{\theta}^2 \sin \frac{\pi}{2} t, \ddot{z} = -\frac{1}{2} r \dot{\theta}^2 \cos \frac{\pi}{2} t$
 $\ddot{x} = -\frac{\sqrt{3}}{2} \frac{\pi^2}{2} \cos \frac{\pi}{2} t, \ddot{y} = -\frac{\pi^2}{2} \sin \frac{\pi}{2} t, \ddot{z} = \frac{1}{2} \frac{\pi^2}{2} \cos \frac{\pi}{2} t$
 Note that position relationships do not include the constants associated with the origin position.

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

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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 **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

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