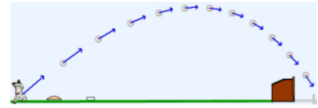
21.1.1 MG road-map: Projectile motion (2D)

A baseball (particle Q) flies over Earth N (a Newtonian reference frame). Aerodynamic forces on the baseball are modeled as $-b\,\vec{\mathbf{v}}$ ($\vec{\mathbf{v}}$ is Q's velocity in N).
$\hat{\mathbf{n}}_x$ is horizontally-right, $\hat{\mathbf{n}}_y$ is vertically-upward, and N_o is home-plate (point fixed in N).



MG road-map for projectile motion x and y ($\hat{\mathbf{n}}_x$, $\hat{\mathbf{n}}_y$ measures of Q's position vector from N_o)

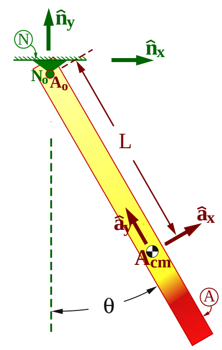
Variable	Translate/ Rotate	Direction (unit vector)	System S	FBD of S	About point	***MG road-map equation***
x	Translate	$\hat{\mathbf{n}}_x$	Q	Draw	Not applicable	$\hat{\mathbf{n}}_x \cdot (\vec{\mathbf{F}}^{Q} \overset{(20.1)}{=} m^Q\,{}^N\vec{\mathbf{a}}^Q)$
y	Translate	$\hat{\mathbf{n}}_y$	Q	Draw	Not applicable	$\hat{\mathbf{n}}_y \cdot (\vec{\mathbf{F}}^{Q} \overset{(20.1)}{=} m^Q\,{}^N\vec{\mathbf{a}}^Q)$
x		**Dot(Nx>, Q.GetDynamics())**				**M**otion**G**enesis command ©
y		**Dot(Ny>, Q.GetDynamics())**				**M**otion**G**enesis command ©

Draw FBD

Solution and simulation link at **www.MotionGenesis.com** ⇒ **Textbooks** ⇒ **Resources**.

21.1.2 MG road-map: Rigid body pendulum (2D)

A non-uniform density rigid rod A is attached at point A_o of A by a frictionless revolute/pin joint to Earth N (Newtonian reference frame). The rod swings with a "pendulum angle" θ in a vertical plane that is perpendicular to unit vector $\hat{\mathbf{a}}_z$.

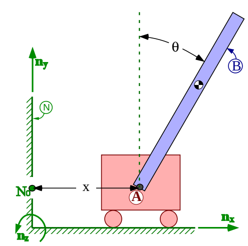


Variable	Translate/ Rotate	Direction (unit vector)	System S	FBD of S	About point	***MG road-map equation***
θ	Rotate	$\hat{\mathbf{a}}_z = \hat{\mathbf{n}}_z$	A	Draw	A_o	$\hat{\mathbf{a}}_z \cdot (\vec{\mathbf{M}}^{A/A_o} \overset{(20.4)}{=} \frac{{}^N d\; {}^N\vec{\mathbf{H}}^{A/A_o}}{dt})$
θ		**Dot(Az>, A.GetDynamics(Ao))**				**M**otion**G**enesis command ©

Solution and simulation link at **www.MotionGenesis.com** ⇒ **Textbooks** ⇒ **Resources**.

21.1.3 MG road-map: Inverted pendulum on cart (x and θ) (2D)

A rigid rod B is pinned to a massive cart A (modeled as a particle) that translates horizontally in a Newtonian reference frame N. The cart's position vector from a point N_o fixed in N is $x\,\hat{\mathbf{n}}_x$ ($\hat{\mathbf{n}}_x$ is horizontally-right). B's swinging motion in N is in a vertical plane perpendicular to $\hat{\mathbf{n}}_z$ (a unit vector fixed in both B and N).



Variable	Translate/ Rotate	Direction (unit vector)	System S	FBD of S	About point	***MG road-map equation***
x	Translate	$\hat{\mathbf{n}}_x$	A, B	Draw	Not applicable	$\hat{\mathbf{n}}_x \cdot (\vec{\mathbf{F}}^{S} \overset{(20.1)}{=} m^S * {}^N\vec{\mathbf{a}}^{S_{cm}})$
θ	Rotate	$\hat{\mathbf{b}}_z = \hat{\mathbf{n}}_z$	B	Draw	A	$\hat{\mathbf{b}}_z \cdot (\vec{\mathbf{M}}^{B/A} \overset{(20.4)}{=} \frac{{}^N d\; {}^N\vec{\mathbf{H}}^{B/A}}{dt} + \ldots)$
x		**Dot(Nx>, System(A, B).GetDynamics())**				**M**otion**G**enesis command ©
θ		**Dot(Bz>, B.GetDynamics(A))**				**M**otion**G**enesis command ©

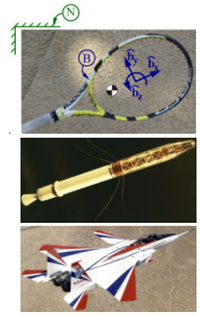
Homework 15.8 and Chapter 25 complete these calculations.

21.1.4 MG road-map: Rotating rigid body (3D)

Shown right is a rotating rigid body B (e.g., tennis racquet, spacecraft, or aircraft) in a Newtonian reference frame N. Right-handed orthogonal unit vectors $\hat{\mathbf{b}}_x$, $\hat{\mathbf{b}}_y$, $\hat{\mathbf{b}}_z$ are fixed in B.

Variable	Translate/ Rotate	Direction (unit vector)	System S	FBD of S	About point	*MG road-map equation*
ω_x	Rotate	$\hat{\mathbf{b}}_x$	B	**Draw**	B_{cm}	$\hat{\mathbf{b}}_x \cdot \left(\vec{\mathbf{M}}^{B/B_{cm}} \underset{(20.4)}{=} \frac{{}^N d\ {}^N\vec{\mathbf{H}}^{B/B_{cm}}}{dt} \right)$
ω_y	Rotate	$\hat{\mathbf{b}}_y$	B	**Draw**	B_{cm}	$\hat{\mathbf{b}}_y \cdot \left(\vec{\mathbf{M}}^{B/B_{cm}} \underset{(20.4)}{=} \frac{{}^N d\ {}^N\vec{\mathbf{H}}^{B/B_{cm}}}{dt} \right)$
ω_z	Rotate	$\hat{\mathbf{b}}_z$	B	**Draw**	B_{cm}	$\hat{\mathbf{b}}_z \cdot \left(\vec{\mathbf{M}}^{B/B_{cm}} \underset{(20.4)}{=} \frac{{}^N d\ {}^N\vec{\mathbf{H}}^{B/B_{cm}}}{dt} \right)$

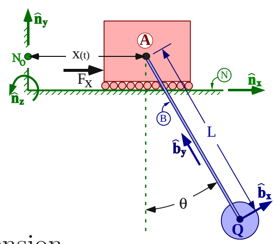
ω_x	**Dot(Bx>, B.GetDynamics(Bcm))**	**M**otion**G**enesis command ©
ω_y	**Dot(By>, B.GetDynamics(Bcm))**	**M**otion**G**enesis command ©
ω_z	**Dot(Bz>, B.GetDynamics(Bcm))**	**M**otion**G**enesis command ©



Solution and simulation link at **www.MotionGenesis.com** ⇒ **Textbooks** ⇒ **Resources**.

Note: The "about point" is somewhat arbitrary. When B_{cm} is chosen: ${}^N\vec{\mathbf{H}}^{B/B_{cm}} \underset{(15.2)}{=} \vec{\vec{\mathbf{I}}}^{B/B_{cm}} \cdot {}^N\vec{\boldsymbol{\omega}}^B$.

21.1.5 MG road-map: Bridge crane equations of motion (2D)



A payload (particle) Q is welded to a light rigid cable B which swings in a Newtonian frame N. Cable B is pinned to a massive trolley A that can move horizontally along a smooth slot fixed in N with a **specified** (known) displacement $x(t)$. A translational actuator with force measure F_x connects trolly A to point N_o of N.

MG road-map for pendulum angle θ, actuator force F_x, and cable tension

Variable	Translate/ Rotate	Direction (unit vector)	System S	FBD of S	About point	*MG road-map equation*
θ	Rotate	$\hat{\mathbf{n}}_z = \hat{\mathbf{b}}_z$	B, Q	**Draw**	A	$\hat{\mathbf{n}}_z \cdot \left(\vec{\mathbf{M}}^{S/A} = \frac{{}^N d\ {}^N\vec{\mathbf{H}}^{S/A}}{dt} + \ldots \right)$
F_x	Translate	$\hat{\mathbf{n}}_x$	A, B, Q	**Draw**	Not applicable	$\hat{\mathbf{n}}_x \cdot \left(\vec{\mathbf{F}}^S = m^S\ {}^N\vec{\mathbf{a}}^{S_{cm}} \right)$
Tension	Translate	$\hat{\mathbf{b}}_y$	A, B, Q	**Draw**	Not applicable	$\hat{\mathbf{n}}_x \cdot \left(\vec{\mathbf{F}}^Q = m^Q\ {}^N\vec{\mathbf{a}}^Q \right)$

θ	**Dot(Nz>, System(B, Q).GetDynamics(A))**	**M**otion**G**enesis command ©
F_x	**Dot(Nx>, System(A, B, Q).GetDynamics( ))**	**M**otion**G**enesis command ©

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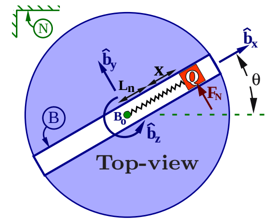
Note: Only the θ road-map equation is needed to predict this system's motion. The others are shown for illustrative purposes.

21.1.6 MG road-map: Particle on spinning slot (2D)



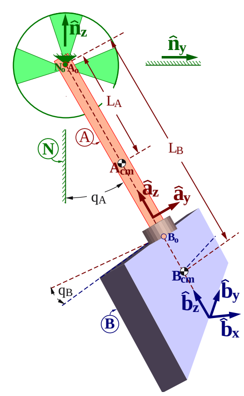
A particle Q slides on a straight slot B. The slot is connected with a revolute joint to a Newtonian frame N at point B_o so that B rotates in a horizontal plane perpendicular to $\hat{\mathbf{b}}_z$ ($\hat{\mathbf{b}}_z$ is vertically-upward and fixed in both B and N).
Note: Homework 14.7 completes the MG road-map calculations for x and θ.

MG road-map for x, θ, and F_N ($\hat{\mathbf{b}}_y$ measure of normal force on Q from B)

Variable	Translate/ Rotate	Direction (unit vector)	System S	FBD of S	About point	***MG road-map equation***
x	Translate	$\hat{\mathbf{b}}_x$	Q	Draw	Not applicable	$\hat{\mathbf{b}}_x \cdot (\vec{\mathbf{F}}^Q = m^Q \, {}^N\vec{\mathbf{a}}^Q)$
θ	Rotate	$\hat{\mathbf{b}}_z$	B, Q	Draw	B_o	$\hat{\mathbf{b}}_z \cdot (\vec{\mathbf{M}}^{S/B_o} = \frac{{}^N d \, {}^N\vec{\mathbf{H}}^{S/B_o}}{dt})$
F_N	Translate	$\hat{\mathbf{b}}_y$	Q	Draw	Not applicable	$\hat{\mathbf{b}}_y \cdot (\vec{\mathbf{F}}^Q = m^Q \, {}^N\vec{\mathbf{a}}^Q)$
x	Dot(Bx>, Q.GetDynamics())					**M**otion**G**enesis command ©
θ	Dot(Bz>, System(B, Q).GetDynamics(Bo))					**M**otion**G**enesis command ©
F_N	Dot(By>, Q.GetDynamics())					**M**otion**G**enesis command ©

Note: The F_N road-map equation is needed to predict motion **if** a friction force depends on $\mu \, F_N$.

21.1.7 MG road-map: Motion of a chaotic double pendulum (3D)



Shown right is a mechanical model of a swinging babyboot (uniform plate B) attached by a shoelace (thin uniform rod A) to a fixed rigid support N. Rod A is attached to N by a revolute joint at point N_o of N. B is attached to A with a second revolute joint at point B_o so B can rotate freely about A's axis.
Note: The revolute joints' axes are ***perpendicular***, not parallel.

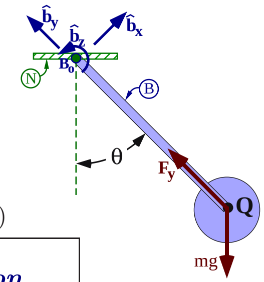
- The plate, rod, and support are rigid.
- The revolute joints are ideal (massless, frictionless, no slop/flexibility).
- Earth is a Newtonian reference frame N.
- Forces due to Earth's gravitation are uniform and constant.
- Other distance forces (electromagnetic and gravitational) and air-resistance are negligible.

Right-handed sets of unit vectors $\hat{\mathbf{n}}_x, \hat{\mathbf{n}}_y, \hat{\mathbf{n}}_z$; $\hat{\mathbf{a}}_x, \hat{\mathbf{a}}_y, \hat{\mathbf{a}}_z$; $\hat{\mathbf{b}}_x, \hat{\mathbf{b}}_y, \hat{\mathbf{b}}_z$ are fixed in N, A, B, respectively, with $\hat{\mathbf{n}}_x = \hat{\mathbf{a}}_x$ parallel to the revolute axis joining A to N, $\hat{\mathbf{n}}_z$ vertically-upward, $\hat{\mathbf{a}}_z = \hat{\mathbf{b}}_z$ parallel to the rod's long axis (and the revolute axis joining B to A), and $\hat{\mathbf{b}}_z$ perpendicular to plate B. q_A is the angle from $\hat{\mathbf{n}}_z$ to $\hat{\mathbf{a}}_z$ with $+\hat{\mathbf{n}}_x$ sense. q_B is the angle from $\hat{\mathbf{a}}_y$ to $\hat{\mathbf{b}}_y$ with $+\hat{\mathbf{a}}_z$ sense.

Variable	Translate/ Rotate	Direction (unit vector)	System S	FBD of S	About point	***MG road-map equation***
q_A	Rotate	$\hat{\mathbf{a}}_x$	A, B	Draw	A_o	$\hat{\mathbf{a}}_x \cdot (\vec{\mathbf{M}}^{S/A_o} = \frac{{}^N d \, {}^N\vec{\mathbf{H}}^{S/A_o}}{dt})$
q_B	Rotate	$\hat{\mathbf{b}}_z$	B	Draw	B_{cm}	$\hat{\mathbf{b}}_z \cdot (\vec{\mathbf{M}}^{B/B_{cm}} = \frac{{}^N d \, {}^N\vec{\mathbf{H}}^{B/B_{cm}}}{dt})$
q_A	Dot(Ax> , System(A, B).GetDynamics(Ao))					**M**otion**G**enesis command ©
q_B	Dot(Bz> , B .GetDynamics(Bcm))					**M**otion**G**enesis command ©

Solution and simulation link at www.MotionGenesis.com ⇒ Textbooks ⇒ Resources.
Note: The "about point" for the q_B road-map can be shifted from B_o to B_{cm} since $\hat{\mathbf{b}}_z \cdot \vec{\mathbf{M}}^{B/B_{cm}} \underset{(17.4)}{=} \hat{\mathbf{b}}_z \cdot \vec{\mathbf{M}}^{B/B_o}$.

21.1.8 MG road-map: Particle pendulum (2D) – angle and tension



A particle Q is welded to the distal end of a light rigid rope B. The rope's other end attaches to a point B_o, fixed in a Newtonian reference frame N. The swinging motion of B and Q is in a vertical plane that is perpendicular to unit vector $\hat{\mathbf{b}}_z$.

MG road-map for pendulum angle θ and tension F_y ($\hat{\mathbf{b}}_y$ measure of force on Q from B)

Variable	Translate/ Rotate	Direction (unit vector)	System S	FBD of S	About point	***MG road-map equation***
θ	Rotate	$\hat{\mathbf{b}}_z$	B, Q	Draw	B_o	$\hat{\mathbf{b}}_z \cdot (\vec{\mathbf{M}}^{S/B_o} \overset{(20.4)}{=} \frac{{}^N d \; {}^N\vec{\mathbf{H}}^{S/B_o}}{dt})$
F_y	Translate	$\hat{\mathbf{b}}_y$	Q	Draw	Not applicable	$\hat{\mathbf{b}}_y \cdot (\vec{\mathbf{F}}^Q \overset{(20.1)}{=} m^Q \; {}^N\vec{\mathbf{a}}^Q)$
θ	**Dot(Bz>, System(B, Q).GetDynamics(Bo))**					**M**otion**G**enesis command ©
F_y	**Dot(By>, Q.GetDynamics( ))**					**M**otion**G**enesis command ©

Draw FBDs

Solution and simulation link at **www.MotionGenesis.com** ⇒ **Textbooks** ⇒ **Resources**.
Note: Only the θ road-map equation is needed to predict motion. The other is shown for illustrative purposes.

21.1.9 MG road-map: Dynamicist on a turntable (ice-skater)

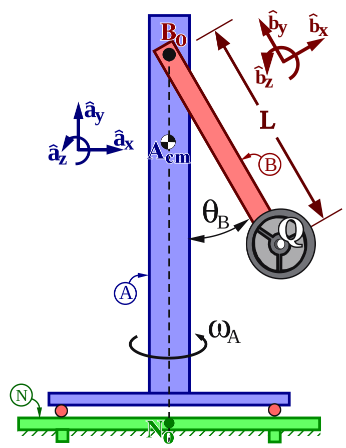
A dynamics instructor stands on a spinning turntable and swings a heavy dumbbell Q inward and outward to change his spin-rate (similar to the ice-skater).
Q is modeled as a particle rigidly attached (welded) to the end of the instructor's hands.

The schematic (below-right) shows a rigid body A (modeling the instructor's legs, torso, and head) that rotates (without friction) relative to Earth (a Newtonian reference frame N) about a vertical axis that is fixed in both A and N and which passes through both point N_o of N and point A_{cm} (A's center of mass).

A massless rigid arm B (modeling the instructor's arms and hands) attaches to A by a revolute motor (shoulder/muscles) whose revolute axis is horizontal and located at point B_o of B (B_o lies on the vertical axis connecting N_o and A_{cm}).

The motor (muscles) **specifies** B's angle θ_B relative to A to change in a known (prescribed) manner from 0 to π rad in 4 seconds ($\theta_B = \pi \frac{t}{4}$).

Right-handed orthogonal unit vectors $\hat{\mathbf{a}}_x$, $\hat{\mathbf{a}}_y$, $\hat{\mathbf{a}}_z$ and $\hat{\mathbf{b}}_x$, $\hat{\mathbf{b}}_y$, $\hat{\mathbf{b}}_z$ are fixed in A and B, respectively, with $\hat{\mathbf{a}}_y$ vertically-upward, $\hat{\mathbf{b}}_z = \hat{\mathbf{a}}_z$ parallel to the revolute motor's axis, and $\hat{\mathbf{b}}_y$ directed from Q to B_o.



Quantity	Symbol	Type	Value
Earth's gravitational constant	g	Constant	$9.8 \; \frac{m}{s^2}$
Distance between Q and B_o	L	Constant	0.7 m
Mass of Q	m	Constant	12 kg
A's moment of inertia about line $\overline{A_{cm} B_o}$	I_{yy}	Constant	0.6 kg m^2
Angle from $\hat{\mathbf{a}}_y$ to $\hat{\mathbf{b}}_y$ with $^+\hat{\mathbf{a}}_z$ sense	θ_B	**Specified**	**$0.25\,\pi\,$t** rad
$\hat{\mathbf{a}}_y$ measure of A's angular velocity in N	ω_A	Variable	

Complete the ***MG road-map*** for the turntable's "spin-rate" ω_A (Note: The "about point" is not unique)

Variable	Translate/ Rotate	Direction (unit vector)	System S	FBD of S	About point	***MG road-map equation***
ω_A	Rotate	$\hat{\mathbf{a}}_y$	A, B, Q	Draw	B_o	$\hat{\mathbf{a}}_y \cdot (\vec{\mathbf{M}}^{S/B_o} = \frac{{}^N d \; {}^N\vec{\mathbf{H}}^{S/B_o}}{dt})$
ω_A	**Dot(Ay> , System(A, B, Q).GetDynamics(Bo))**					**M**otion**G**enesis command ©

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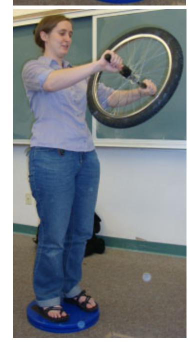
21.1.10 MG road-map: Instructor on turntable with spinning wheel (3D)



The pictures to the right shows dynamicist Dr. G standing on a spinning turntable and holding a spinning bicycle wheel.

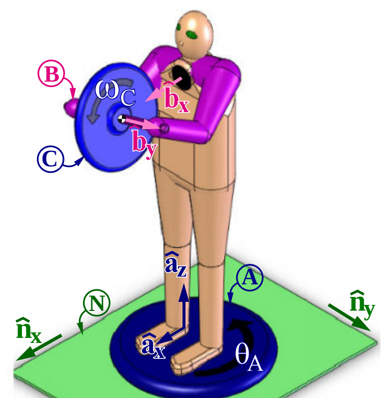
The mechanical model (below right) has a rigid body A (modeling the turntable, legs, torso, and head) that can freely rotate relative to Earth (Newtonian reference frame N) about a vertical axis that is fixed in both A and N and which passes through the center of the turntable (point N_o) and A_{cm} (A's center of mass).

A light (massless) rigid frame B (modeling the shoulders, arms, hands, and a portion of the bicycle wheel's axle) is attached to A by a revolute motor at point B_o of B (B_o lies on the vertical axis passing through A_{cm}). The motor's revolute axis passes through points B_o and C_{cm}, is horizontal, and is parallel to $\widehat{\mathbf{b}}_x = \widehat{\mathbf{a}}_x$.

A rigid bicycle wheel C is attached to B by a frictionless revolute joint whose axis passes through C_{cm} (C's center of mass) and is parallel to $\widehat{\mathbf{b}}_y$.

Right-handed orthogonal unit vectors $\widehat{\mathbf{a}}_x$, $\widehat{\mathbf{a}}_y$, $\widehat{\mathbf{a}}_z$ and $\widehat{\mathbf{n}}_x$, $\widehat{\mathbf{n}}_y$, $\widehat{\mathbf{n}}_z$ are fixed in A and N, respectively. Initially $\widehat{\mathbf{a}}_i = \widehat{\mathbf{n}}_i$ $(i = x, y, z)$, and then rigid body A is subjected to a right-handed rotation characterized by $\theta_A\,\widehat{\mathbf{a}}_z$ where $\widehat{\mathbf{a}}_z = \widehat{\mathbf{n}}_z$ is directed vertically-upward and $\widehat{\mathbf{a}}_x$ points from Dr. G's back to front (parallel to the axis of the revolute motor connecting A and B).

Unit vectors $\widehat{\mathbf{b}}_x$, $\widehat{\mathbf{b}}_y$, $\widehat{\mathbf{b}}_z$ are fixed in B. Initially $\widehat{\mathbf{b}}_i = \widehat{\mathbf{a}}_i$ $(i = x, y, z)$, then B is subjected to a $\theta_B\,(\widehat{\mathbf{a}}_x = \widehat{\mathbf{b}}_x)$ right-handed rotation in A where $\widehat{\mathbf{b}}_y$ is directed along the wheel's axle from Dr. G's right-to-left hand. Dr. G changes θ_B in a **specified** sinusoid manner with amplitude 30° and period 4 seconds.



Courtesy Doug Schwandt
Purchase turntable/bicycle wheel at Arbor-scientific

Quantity	Symbol and type		Value
Mass of C	m^C	Constant	2 kg
Distance between B_o and C_{cm}	L_x	Constant	0.5 m
A's moment of inertia about B_o for $\widehat{\mathbf{a}}_z$	I^A_{zz}	Constant	0.64 kg m^2
C's moment of inertia about C_{cm} for $\widehat{\mathbf{b}}_x$	I^C	Constant	0.12 kg m^2
C's moment of inertia about C_{cm} for $\widehat{\mathbf{b}}_y$	J^C	Constant	0.24 kg m^2
Angle from $\widehat{\mathbf{n}}_x$ to $\widehat{\mathbf{a}}_x$ with $^+\widehat{\mathbf{n}}_z$ sense	θ_A	Variable	
Angle from $\widehat{\mathbf{a}}_y$ to $\widehat{\mathbf{b}}_y$ with $^+\widehat{\mathbf{a}}_x$ sense	θ_B	**Specified**	$\frac{\pi}{6}\sin(\frac{\pi}{2}\,t)$
$\widehat{\mathbf{b}}_y$ measure of C's angular velocity in B	ω_C	Variable	

Complete the ***MG road-map*** for θ_A and ω_C (the "about points" are not unique).

Variable	Translate/ Rotate	Direction (unit vector)	System S	FBD of S	About point	MG road-map equation
θ_A	Rotate	$\widehat{\mathbf{a}}_z$	A, B, C	Draw	B_o	$\widehat{\mathbf{a}}_z \cdot (\vec{\mathrm{M}}^{S/B_o} = \frac{^N d\ ^N\vec{\mathrm{H}}^{S/B_o}}{dt})$
ω_C	Rotate	$\widehat{\mathbf{b}}_y$	C	Draw	C_{cm}	$\widehat{\mathbf{b}}_y \cdot (\vec{\mathrm{M}}^{C/C_{cm}} = \frac{^N d\ ^N\vec{\mathrm{H}}^{C/C_{cm}}}{dt})$
θ_A		**Dot(Az> , System(A,B,C).GetDynamics(Bo))**				**M**otion**G**enesis command ©
ω_C		**Dot(By> , C .GetDynamics(Ccm))**				**M**otion**G**enesis command ©

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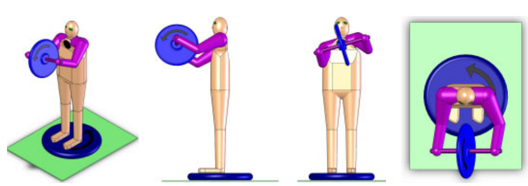
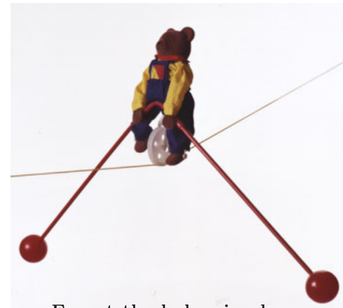


21.1.11 MG road-map: Bear riding a unicycle on a high-wire (3D)

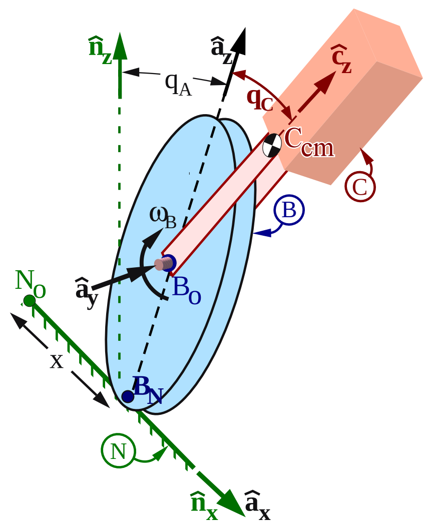
The figures to the right show a (massless) pulley-wheel B that **rolls** along a taut (rigid) cable N (fixed on Earth, a Newtonian frame). Rigid body C (seat, rider, and balancing poles) attach to B with an ideal revolute motor at B_o (B's centroid). The motor axis is aligned with B's symmetry axis.

Right-handed orthogonal unit vectors $\hat{\mathbf{n}}_x$, $\hat{\mathbf{n}}_y$, $\hat{\mathbf{n}}_z$ are fixed in N with $\hat{\mathbf{n}}_z$ vertically-upward and $\hat{\mathbf{n}}_x$ directed horizontally along the cable from a point N_o (fixed in N) to B_N (B's rolling point of contact with N).

Right-handed orthogonal unit vectors $\hat{\mathbf{a}}_x$, $\hat{\mathbf{a}}_y$, $\hat{\mathbf{a}}_z$ are directed with $\hat{\mathbf{a}}_x = \hat{\mathbf{n}}_x$, $\hat{\mathbf{a}}_y$ parallel to the motor axis, and $\hat{\mathbf{a}}_z$ from B_N to B_o.



Ernest the balancing bear
Purchase at Schylling toy



Right-handed unit vectors $\hat{\mathbf{c}}_x$, $\hat{\mathbf{c}}_y$, $\hat{\mathbf{c}}_z$ are parallel to C's principal inertia axes about C_{cm} (C's center of mass), with $\hat{\mathbf{c}}_y = \hat{\mathbf{a}}_y$ and $\hat{\mathbf{c}}_z$ from B_o to C_{cm} (with balancing poles, C_{cm} is below B_o and L_C is negative).

Quantity	Symbol	Type	Value
Earth's gravitational constant	g	Constant	$9.8\ \text{m/s}^2$
Radius of B	r_B	Constant	30 cm
$\hat{\mathbf{c}}_z$ measure of C_{cm}'s position vector from B_o	L_C	Constant	–35 cm
Mass of C	m^C	Constant	2 kg
C's moment of inertia about C_{cm} for $\hat{\mathbf{c}}_x$	I	Constant	$3.4\ \text{kg m}^2$
C's moment of inertia about C_{cm} for $\hat{\mathbf{c}}_y$	J	Constant	$3.2\ \text{kg m}^2$
C's moment of inertia about C_{cm} for $\hat{\mathbf{c}}_z$	K	Constant	$2.8\ \text{kg m}^2$
$\hat{\mathbf{a}}_y$ measure of motor torque on B from C	T_y	**Specified**	below
Angle from $\hat{\mathbf{n}}_z$ to $\hat{\mathbf{a}}_z$ with $^-\hat{\mathbf{n}}_x$ sense	q_A	Variable	
$\hat{\mathbf{a}}_y$ measure of $^A\vec{\boldsymbol{\omega}}^B$ ($^A\vec{\boldsymbol{\omega}}^B = \omega_B\,\hat{\mathbf{a}}_y$)	ω_B	Variable	
Angle from $\hat{\mathbf{a}}_z$ to $\hat{\mathbf{c}}_z$ with $^+\hat{\mathbf{a}}_y$ sense	q_C	Variable	
$\hat{\mathbf{n}}_x$ measure of $\vec{\mathbf{r}}^{\,B_N/N_o}$	x	Variable	

Form a complete set of ***MG road-maps*** for this systems's equations of motion (solution is not unique).
If necessary, add more ***MG road-maps*** so there are the same number of equations as unknowns.

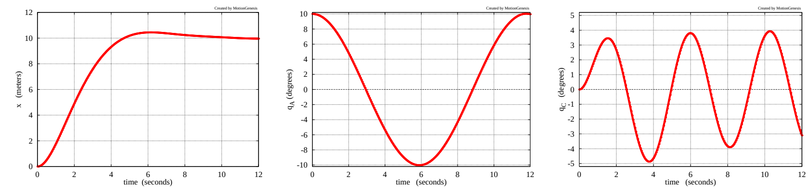
Variable	Translate/ Rotate	Direction (unit vector)	System S	FBD of S	About point	***MG road-map equation***	Additional Unknowns
q_A	Rotate	$\hat{\mathbf{a}}_x$	A,B,C	**Draw**	B_N	$\hat{\mathbf{a}}_x \cdot (\ \vec{\mathbf{M}}^{S/B_N} \underset{(20.4)}{=} \frac{^N d\ ^N\vec{\mathbf{H}}^{S/B_N}}{dt} + \ldots)$	
ω_B	Rotate	$\hat{\mathbf{a}}_y$	B, C	**Draw**	B_N	$\hat{\mathbf{a}}_y \cdot (\ \vec{\mathbf{M}}^{S/B_N} \underset{(20.4)}{=} \frac{^N d\ ^N\vec{\mathbf{H}}^{S/B_N}}{dt} + \ldots)$	
q_C	Rotate	$\hat{\mathbf{a}}_y$	C	**Draw**	B_o	$\hat{\mathbf{a}}_y \cdot (\ \vec{\mathbf{M}}^{C/B_o} \underset{(20.4)}{=} \frac{^N d\ ^N\vec{\mathbf{H}}^{C/B_o}}{dt} + \ldots)$	
x	Translate	$\hat{\mathbf{a}}_x$	A,B,C	**Draw**	Not applicable	$\hat{\mathbf{a}}_x \cdot (\ \vec{\mathbf{F}}^S \underset{(20.1)}{=} m^S * {}^N\vec{\mathbf{a}}^{S_{cm}}\ )$	* F_x

***** Additional scalar constraint equation(s): $\dot{x} - r\,\omega_B = 0$
MG road-map for ω_B is not unique. Alternate (allows for sliding): "System" B, "About point" B_o, "Additional unknown" F_x.
Instructor notes: One way to eliminate F_x from this analysis is to solve $\dot{x} = r\,\omega_B$ and eliminate the MG road-map for x.

q_A	Dot(**Ax>** , System(**A, B, C**).GetDynamics(B_N))	**M**otion**G**enesis command ©
ω_B	Dot(**Ay>** , System(**B, C**).GetDynamics(B_N))	**M**otion**G**enesis command ©
q_C	Dot(**Ay>** , C.GetDynamics(B_o))	**M**otion**G**enesis command ©
x	Dot(**Ax>** , System(**A, B, C**).GetDynamics())	**M**otion**G**enesis command ©
	`SolveDt( x' - r*wB = 0, x' )`	**M**otion**G**enesis command ©

To move the unicycle to $x_{\text{Desired}} = 10$ m, use a "PD control law" with $T_y = -0.3\,(x - x_{\text{Desired}}) - 0.6\,\dot{x}$.

Optional simulation:
Plot x, q_A, q_C for $0 \le t \le 12$ sec.
Use initial values:
$x = 0$ m $\quad q_A = 10^\circ \quad q_C = 0^\circ$
$\dot{x} = 0 \quad \dot{q}_A = 0 \quad \dot{q}_C = 0$

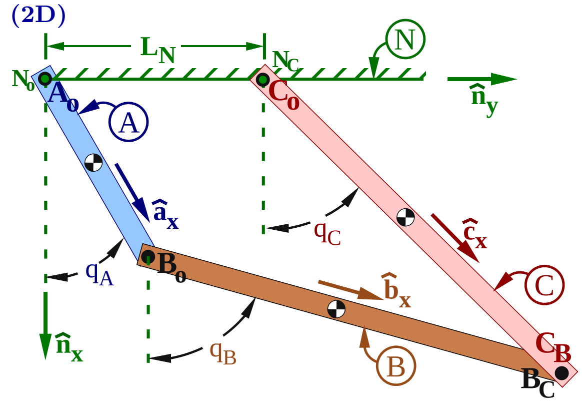


Solution at **www.MotionGenesis.com** ⇒ **Get Started** ⇒ **Bear on rolling unicycle**.

21.1.12 MG road-map: Four-bar linkage statics (2D)

The figure to the right shows a planar four-bar linkage consisting of frictionless-pin-connected uniform rigid links A, B, and C and ground N.

- Link A connects to N and B at points A_o and A_B
- Link B connects to A and C at points B_o and B_C
- Link C connects to N and B at points C_o and C_B
- Point N_o of N is coincident with A_o
- Point N_C of N is coincident with C_o



Right-handed orthogonal unit vectors $\hat{\mathbf{a}}_i$, $\hat{\mathbf{b}}_i$, $\hat{\mathbf{c}}_i$, $\hat{\mathbf{n}}_i$ $(i = x, y, z)$ are fixed in A, B, C, N, with:

- $\hat{\mathbf{a}}_x$ directed from A_o to A_B
- $\hat{\mathbf{b}}_x$ directed from B_o to B_C
- $\hat{\mathbf{c}}_x$ directed from C_o to C_B
- $\hat{\mathbf{n}}_x$ vertically-downward
- $\hat{\mathbf{n}}_y$ directed from N_o to N_C
- $\hat{\mathbf{a}}_z = \hat{\mathbf{b}}_z = \hat{\mathbf{c}}_z = \hat{\mathbf{n}}_z$ parallel to pin axes

Quantity	Symbol	Value
Length of link A	L_A	1 m
Length of link B	L_B	2 m
Length of link C	L_C	2 m
Distance between N_o and N_C	L_N	1 m
Mass of A	m^A	10 kg
Mass of B	m^B	20 kg
Mass of C	m^C	20 kg
Earth's gravitational acceleration	g	9.81 $\frac{\text{m}}{\text{s}^2}$
$\hat{\mathbf{n}}_y$ measure of force applied to C_B	H	200 N
Angle from $\hat{\mathbf{n}}_x$ to $\hat{\mathbf{a}}_x$ with $^+\hat{\mathbf{n}}_z$ sense	q_A	Variable
Angle from $\hat{\mathbf{n}}_x$ to $\hat{\mathbf{b}}_x$ with $^+\hat{\mathbf{n}}_z$ sense	q_B	Variable
Angle from $\hat{\mathbf{n}}_x$ to $\hat{\mathbf{c}}_x$ with $^+\hat{\mathbf{n}}_z$ sense	q_C	Variable

As in Hw 8.7, create the following "***loop equation***" and dot-product with $\hat{\mathbf{n}}_x$ and $\hat{\mathbf{n}}_y$.

$$L_A\,\hat{\mathbf{a}}_x + L_B\,\hat{\mathbf{b}}_x - L_C\,\hat{\mathbf{c}}_x - L_N\,\hat{\mathbf{n}}_y = \vec{\mathbf{0}}$$

Complete the following ***MG road-map*** to determine this systems's ***static configuration***.

Variable	Translate/ Rotate	Direction (unit vector)	System S	FBD of S	About point	***MG road-map equation***	Additional Unknowns
q_A	Rotate	$\hat{\mathbf{n}}_z$	A, B	**Draw**	A_o	$\hat{\mathbf{a}}_x \cdot \vec{\mathbf{M}}^{S/A_o} = 0$	F_x^C, F_y^C
q_B	Rotate	$\hat{\mathbf{n}}_z$	B	**Draw**	B_o	$\hat{\mathbf{a}}_y \cdot \vec{\mathbf{M}}^{B/B_o} = 0$	F_x^C, F_y^C
q_C	Rotate	$\hat{\mathbf{n}}_z$	C	**Draw**	C_o	$\hat{\mathbf{a}}_y \cdot \vec{\mathbf{M}}^{C/C_o} = 0$	F_x^C, F_y^C

* Additional scalar constraint equation: $-L_A \sin(q_A)\,\dot{q}_A - L_B \sin(q_B)\,\dot{q}_B + L_C \sin(q_C)\,\dot{q}_C = 0$

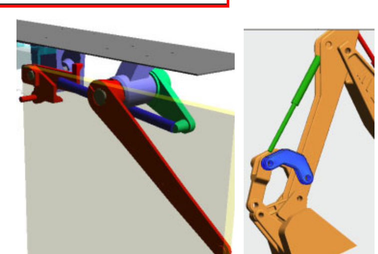
* Additional scalar constraint equation: $L_A \cos(q_A)\,\dot{q}_A + L_B \cos(q_B)\,\dot{q}_B - L_C \cos(q_C)\,\dot{q}_C = 0$

q_A	**Dot(Nz> , System(A, B).GetStatics(Ao))**	**M**otion**G**enesis command ©
q_B	**Dot(Nz> , B .GetStatics(Bo))**	**M**otion**G**enesis command ©
q_C	**Dot(Nz> , C.GetStatics(Co))**	**M**otion**G**enesis command ©

Determine the ***static equilibrium*** values of q_A, q_B, q_C.
Use your intuition (**guess**), circle the ***stable*** solution.

Solution 1	$q_A \approx 20.0^\circ$	$q_B \approx 71.7^\circ$	$q_C = 38.3^\circ$
Solution 2	$q_A \approx 249.3^\circ$	$q_B \approx 140.2^\circ$	$q_C = 199.1^\circ$
Solution 3	$q_A \approx 30.7^\circ$	$q_B \approx 226.1^\circ$	$q_C = 254.7^\circ$

Solution at **www.MotionGenesis.com** ⇒ **Get Started** ⇒ **Four-bar linkage**



SimWise 4-bar linkages.
Courtesy Design Simulation Technology