

# Contents

Dynamics – what does it do for us? . . . . .	i
Newton’s three laws . . . . .	ii
Methods for forming equations of motion . . . . .	iii
<b>1 Math review</b>	<b>1</b>
1.1 Why math is important . . . . .	1
1.2 Units - SI and U.S. . . . .	1
1.3 Geometry: Ancient Euclid and modern vectors . . . . .	2
1.4 Circles and their properties . . . . .	2
1.5 Triangles and ratios of their sides (sine, cosine, tangent) . . . . .	2
1.5.1 Properties of sine and cosine and useful trigonometric formulas . . . . .	3
1.5.2 Sine and cosine as functions (Euler, circa 1730) . . . . .	4
1.5.3 The amplitude-phase formulas for sine and cosine . . . . .	4
1.5.4 The <code>atan2</code> function . . . . .	4
1.6 Types of scalars: Variable, Specified, Constant . . . . .	5
1.7 Differentiation . . . . .	5
1.7.1 Definition of an ordinary derivative of a scalar function . . . . .	5
1.7.2 Definition of a partial derivative of a scalar function . . . . .	5
1.7.3 Definition of the differential of an independent variable and scalar function . . . . .	6
1.7.4 Definition of the total derivative of a scalar function . . . . .	6
1.7.5 Short table of derivatives frequently encountered in engineering . . . . .	6
1.7.6 Example: Partial and ordinary differentiation . . . . .	7
1.7.7 Product rule for derivatives . . . . .	7
1.7.8 Quotient rule for derivatives: Use exponents and the product rule . . . . .	7
1.7.9 Chain rule for derivatives . . . . .	7
1.7.10 Implicit differentiation: A useful tool for calculating derivatives . . . . .	7
1.8 Integration and a short table of integrals . . . . .	8
1.9 Minimization and maximization (optimization) . . . . .	9
1.10 Solutions of <i>polynomial</i> equations (roots) . . . . .	11
1.11 Continuous solutions of <i>nonlinear</i> algebraic equations . . . . .	11
<b>2 Vectors</b>	<b>13</b>
2.1 Examples of scalars, vectors, and dyadics . . . . .	13
2.2 Definition of a vector . . . . .	14
2.3 Zero vector $\vec{0}$ and its properties . . . . .	14
2.4 Unit $\hat{v}$ vectors . . . . .	15
2.5 Equal vectors ( = ) . . . . .	15
2.6 Vector addition ( + ) . . . . .	15
2.7 Vector multiplied or divided by a scalar ( * or / ) . . . . .	16
2.8 Vector negation and subtraction ( - ) . . . . .	16
2.9 Vector dot product ( $\cdot$ ) . . . . .	17

2.9.1	Properties of the dot-product $(\cdot)$ . . . . .	17
2.9.2	Uses for the dot-product $(\cdot)$ . . . . .	17
2.9.3	Special case: Dot-products with orthogonal unit vectors . . . . .	18
2.9.4	Examples: Vector dot-products $(\cdot)$ . . . . .	18
2.9.5	Dot-products to change vector equations to scalar equations (see Hw 1.31) . . . . .	18
2.10	Vector cross product $(\times)$ . . . . .	19
2.10.1	Properties of the cross-product $(\times)$ . . . . .	19
2.10.2	Uses for the cross-product $(\times)$ . . . . .	19
2.10.3	Special case: Cross-products with right-handed, orthogonal, unit vectors . . . . .	20
2.10.4	Examples: Vector cross-products $(\times)$ . . . . .	20
2.11	Scalar triple product $(\cdot \times$ or $\times \cdot)$ . . . . .	21
2.11.1	Scalar triple product and the volume of a tetrahedron . . . . .	21
2.11.2	$(\times \cdot)$ to change vector equations to scalar equations (see Hw 1.31) . . . . .	21
<b>3</b>	<b>Position vectors and vector geometry</b> . . . . .	<b>23</b>
3.1	Position of a point (or particle) (see examples in Hw 3) . . . . .	23
3.2	Distance (also see speed and distance-traveled in Section 10.8) . . . . .	24
3.3	Example: Cable lengths, angles, surface area (orthogonal walls) . . . . .	25
3.4	Proof of sine addition formula with vector cross-products . . . . .	26
<b>4</b>	<b>Vector basis</b> . . . . .	<b>27</b>
4.1	What is a vector basis? . . . . .	27
4.2	Rigid and non-rigid bases . . . . .	28
4.3	Non-orthogonal basis . . . . .	28
4.4	Creating various 3D bases from two non-parallel vectors . . . . .	28
4.5	Concept: What is the vector vs. how is it expressed . . . . .	29
4.6	Expressing a vector in terms of basis $\vec{\mathbf{a}}_1, \vec{\mathbf{a}}_2, \vec{\mathbf{a}}_3$ . . . . .	30
4.7	Optional: Coordinate system vs. vector bases . . . . .	31
4.8	Optional: Rigid frame and transformation matrices . . . . .	32
<b>5</b>	<b>Rotation matrices I</b> . . . . .	<b>33</b>
5.1	Uses for the rotation matrix ${}^aR^b$ (for geometry, statics, motion analysis, stress . . . . .)	33
5.2	Rotation matrices and matrix multiplication . . . . .	34
5.3	Rotation matrices - who cares? . . . . .	34
5.4	Simple rotation matrix examples . . . . .	35
5.4.1	Example: Calculating angles between unit vectors $\hat{\mathbf{a}}_x, \hat{\mathbf{a}}_y, \hat{\mathbf{a}}_z$ and $\hat{\mathbf{b}}_x, \hat{\mathbf{b}}_y, \hat{\mathbf{b}}_z$ . . . . .	35
5.4.2	Example: Calculation of rotation matrix inverse (use transpose) . . . . .	35
5.4.3	Example: Rotation matrix for express, dot, and cross . . . . .	35
5.5	Forming rotation matrices and matrix multiplication . . . . .	36
5.5.1	Example: Forming the simple rotation matrix ${}^aR^n$ . . . . .	36
5.5.2	Hug rule (a pattern for quickly forming simple rotation matrices) . . . . .	36
5.5.3	Example: Forming the simple rotation matrix ${}^bR^a$ . . . . .	37
5.5.4	Example: Rotation matrix multiplication to form ${}^bR^n = {}^bR^a * {}^aR^n$ . . . . .	37
5.6	What is an angle? . . . . .	38
5.7	Optional: Proofs . . . . .	39
5.7.1	Proof that a rotation matrix is orthonormal . . . . .	39
5.7.2	Proof of relationship between $\hat{\mathbf{b}}_x, \hat{\mathbf{b}}_y, \hat{\mathbf{b}}_z$ and $\hat{\mathbf{a}}_x, \hat{\mathbf{a}}_y, \hat{\mathbf{a}}_z$ measures of a vector $\vec{\mathbf{v}}$ . . . . .	39

<b>6</b>	<b>Vector differentiation and integration</b>	<b>41</b>
6.1	Differentiation concepts: Changes in magnitude and direction . . . . .	41
6.2	Expressing a vector in terms of vectors fixed in a reference frame . . . . .	42
6.3	Partial and ordinary derivatives of a vector in a reference frame . . . . .	42
6.4	Constant vectors (vectors fixed in a reference frame) . . . . .	42
6.5	Vectors with constant magnitude . . . . .	42
6.6	Properties of ordinary <u>or</u> partial derivatives of vectors . . . . .	43
6.7	Example: Derivatives of a vector . . . . .	43
6.8	Differential of a vector . . . . .	44
6.9	Integral of a vector . . . . .	44
6.10	Optional: Limit of a vector in a reference frame . . . . .	44
6.11	Optional: Differentiation with respect to a vector (gradients) . . . . .	45
6.12	Optional: Proofs . . . . .	46
<b>7</b>	<b>Angular velocity &amp; angular acceleration</b>	<b>47</b>
7.1	Angular velocity concepts: Moon and Earth celestial systems . . . . .	47
7.2	What is a reference frame? . . . . .	48
7.2.1	Orientation of a rigid body (or reference frame) . . . . .	48
7.2.2	Differences between a vector basis, rigid frame, and reference frame . . . . .	48
7.2.3	What is a Newtonian (inertial/fixed) reference frame? . . . . .	48
7.3	Angular velocity and the golden rule for vector differentiation . . . . .	49
7.3.1	Example: Angular velocity and vector differentiation . . . . .	49
7.3.2	Example: Vector differentiation and angular momentum – spinning book . . . . .	49
7.3.3	Simple angular velocity . . . . .	50
7.3.4	Angular velocity negative property . . . . .	51
7.3.5	Angular velocity addition theorem . . . . .	51
7.3.6	Angular velocity example: Chaotic plate pendulum . . . . .	51
7.3.7	Optional: New formula for angular velocity (Mitiguy, 1995) . . . . .	51
7.3.8	Optional: Angular velocity and orthogonal basis vectors . . . . .	52
7.3.9	Optional: Angular velocity and rotation matrices . . . . .	53
7.4	Angular acceleration . . . . .	53
7.4.1	Angular acceleration addition theorem . . . . .	53
7.4.2	Angular acceleration negative property . . . . .	53
7.4.3	Angular acceleration example: Chaotic plate pendulum . . . . .	54
7.4.4	Optional: Second time-derivative of a vector in a reference frame . . . . .	54
7.5	Optional: Angular velocity proofs . . . . .	54
7.5.1	Proof of existence and uniqueness of the defining property of angular velocity . . . . .	54
7.5.2	Proof of the new formula for angular velocity . . . . .	55
7.5.3	Proof of angular velocity and orthogonal basis vectors . . . . .	56
7.5.4	Proof of simple angular velocity . . . . .	56
7.5.5	Proof of angular velocity addition theorem . . . . .	57
7.5.6	Proof of angular velocity negative property . . . . .	57
7.5.7	Proof of $2^{nd}$ time-derivative of any vector . . . . .	57
<b>8</b>	<b>Rotation matrices II</b>	<b>59</b>
8.1	Other representations of orientation (See examples in Hw 7) . . . . .	59
8.2	Euler rotation angles (see appendix of rotation tables) . . . . .	60
8.2.1	Converting Body xyz angles to rotation matrices (also see appendix of rotation tables) . . . . .	60
8.2.2	Converting rotation matrices to Body xyz angles (also see appendix of rotation tables) . . . . .	60
8.2.3	Optional: Space-fixed rotation sequences . . . . .	61
8.3	Case study: Clinical study of pelvis orientation . . . . .	62

8.3.1	Pelvic model . . . . .	62
8.3.2	Body yxz Euler angles [called TOR (tilt-obliquity-rotation) in biomechanics] . . . . .	63
8.3.3	Body zxy Euler angles [called ROT (rotation-obliquity-tilt) in biomechanics] . . . . .	63
8.3.4	Clinical angles (physically measurable angles) . . . . .	64
8.3.5	Summary: Euler angles, clinical angles, and pelvis orientation . . . . .	65
8.4	Simple $\theta \hat{\lambda}$ rotations . . . . .	66
8.4.1	How a simple $\theta \hat{\lambda}$ rotation affects an arbitrary vector $\vec{b}$ fixed in $B$ . . . . .	66
8.4.2	Converting simple $\theta \hat{\lambda}$ rotations to rotation matrices . . . . .	66
8.5	Euler parameters and $\theta \hat{\lambda}$ rotations . . . . .	67
8.5.1	Euler parameters and how a simple $\theta \hat{\lambda}$ rotation affects an arbitrary vector . . . . .	67
8.5.2	Converting Euler parameters to rotation matrices . . . . .	67
8.5.3	Converting rotation matrices to Euler parameters (or $\theta \hat{\lambda}$ or Rodrigues parameters) . . . . .	68
8.5.4	Euler parameters and inverse rotations . . . . .	68
8.5.5	Euler parameters and successive rotations . . . . .	68
8.5.6	Euler parameters and small rotations . . . . .	69
8.5.7	Converting Body xyz angles to Euler parameters . . . . .	69
8.6	Optional: Rodrigues parameters . . . . .	69
8.7	Poisson parameters (9 elements of a rotation matrix) . . . . .	70
8.7.1	Optional: Interdependencies in elements of a rotation matrix . . . . .	70
8.7.2	Optional: Notes about rotation matrices . . . . .	70
8.8	Optional: Indirect determination of orientation . . . . .	70
8.9	Optional: Proofs . . . . .	71
8.9.1	Proof that equation (12) corresponds to a eigenvector of a rotation matrix . . . . .	71
8.9.2	Geometrical proof of how a $\theta \hat{\lambda}$ rotation affects a vector fixed in $B$ . . . . .	71
8.9.3	Mathematical proof of how a $\theta \hat{\lambda}$ rotation affects a vector fixed in $B$ . . . . .	72
8.9.4	Proof of converting simple $\theta \hat{\lambda}$ rotations to rotation matrices . . . . .	72
8.9.5	Proof of Euler parameters to rotation matrix . . . . .	73
8.9.6	Proof of rotation matrix to Euler parameters . . . . .	73
8.9.7	Proof of converting Body xyz angles to Euler parameters . . . . .	74
<b>9</b>	<b>Angular velocity and kinematical ODEs</b> . . . . .	<b>75</b>
9.1	Angular velocity and $\theta \hat{\lambda}$ rotations . . . . .	75
9.1.1	Simple angular velocity - a special case . . . . .	75
9.1.2	Optional: Kinematical differential equations for $\theta$ and $\hat{\lambda}$ . . . . .	76
9.2	Euler vector, Euler parameters (quaternions), and angular velocity . . . . .	76
9.2.1	Constraints associated with Euler parameters . . . . .	76
9.2.2	Optional: Angular velocity in terms of Euler parameters . . . . .	77
9.2.3	Optional: Angular acceleration and Euler parameters . . . . .	77
9.2.4	Optional: $2^{nd}$ -order kinematical differential equations for Euler parameters . . . . .	77
9.2.5	Optional: Euler parameters and small, slow rotations . . . . .	77
9.3	Euler angles, angular velocity, and kinematical ODEs: Example . . . . .	78
9.4	Rotation matrices and angular velocity . . . . .	79
9.4.1	Rotation matrices and angular velocity matrix . . . . .	79
9.4.2	Poisson's kinematical differential equations . . . . .	80
9.4.3	Optional: Time-derivative of the angular velocity matrix . . . . .	80
9.4.4	Optional: $2^{nd}$ -order Poisson kinematical differential equations . . . . .	80
9.5	Optional: Proofs . . . . .	81
9.5.1	Proof of angular velocity in terms of $\theta$ and $\hat{\lambda}$ . . . . .	81
9.5.2	Proof of kinematical differential equations for $\theta$ and $\hat{\lambda}$ . . . . .	82
9.5.3	Proof of Euler's kinematical differential equations . . . . .	83
9.5.4	Proof of angular velocity in terms of Euler parameters . . . . .	83

9.5.5	Proof of angular acceleration and Euler parameters . . . . .	83
9.5.6	Proof of $2^{nd}$ -order differential equations for Euler parameters . . . . .	84
9.5.7	Proof of time-derivative of the angular velocity matrix . . . . .	84
<b>10</b>	<b>Points: Velocity and acceleration</b>	<b>85</b>
10.1	Definition of velocity and acceleration . . . . .	86
10.2	Velocity and acceleration of two points <u>fixed</u> on a rigid body . . . . .	88
10.3	Velocity and acceleration of a point <u>moving</u> on a rigid body . . . . .	89
10.4	Velocity and acceleration of a point using another point . . . . .	91
10.5	Relative velocity and relative acceleration of a point . . . . .	91
10.6	Elongation and elongation-rate . . . . .	92
10.7	Relationship between distance, position, velocity, and acceleration . . . . .	92
10.7.1	Constant acceleration in a reference frame $N$ – a special case . . . . .	92
10.7.2	Constant acceleration along a curve . . . . .	93
10.7.3	Circular motion . . . . .	93
10.7.4	Analogy between translational motion and 2D rotational motion . . . . .	93
10.7.5	Example: Free-fall of a sky-diver with constant downward acceleration . . . . .	93
10.8	Speed and distance-traveled in a reference frame . . . . .	94
10.9	Optional: Definition of jerk (snap, crackle, pop) . . . . .	95
10.10	Optional: Acceleration vocabulary . . . . .	95
10.11	Velocity proofs . . . . .	96
10.11.1	Proof of equivalence of the two relative velocity definitions . . . . .	97
10.11.2	Proof of irrelevance of reference frame for relative velocity of coincident points . . . . .	97
10.11.3	Proof of minimum velocity magnitude/location and instant center . . . . .	98
<b>11</b>	<b>Constraints: Rods, rolling, gears, . . .</b>	<b>99</b>
11.1	Number of degrees of freedom . . . . .	100
11.2	Rods, ropes, and separators (example in Section 11.14) . . . . .	100
11.3	Linear actuator . . . . .	100
11.4	Ball and socket joint . . . . .	100
11.5	Revolute joint (also called a hinge or pin joint) . . . . .	101
11.6	Revolute motor (revolute joint with additional angular constraint) . . . . .	101
11.7	Cylindrical joint (revolute joint on straight slot) . . . . .	101
11.8	Ball and socket in slot . . . . .	101
11.9	Prismatic joint (also called a slider joint or square-slot joint) . . . . .	102
11.10	Universal joint (Hooke's joint) . . . . .	102
11.11	Contact (an intermittent inequality constraint) . . . . .	102
11.12	Sliding, rolling, and pure rolling (contact) . . . . .	103
11.12.1	Example: Velocity, sliding, rolling, and two points fixed on a rigid object . . . . .	103
11.12.2	Example: Acceleration, sliding, rolling, and two points fixed on a rigid object . . . . .	103
11.12.3	Example: Rolling motions of a cylinder inside a cylinder . . . . .	104
11.13	Gears and constraint equations . . . . .	105
11.14	Constraints associated with cables supporting a platform . . . . .	107
11.15	Optional: Constraint stabilization . . . . .	108
<b>12</b>	<b>Particles (points with mass)</b>	<b>109</b>
12.1	System of particles . . . . .	110
12.2	Translational (linear) momentum for particles . . . . .	110
12.3	Angular momentum and shift theorem for particles . . . . .	111
12.4	Kinetic energy for particles . . . . .	112
12.5	Effective force of a particle . . . . .	113
12.5.1	Effective force of a system of particles . . . . .	113

12.5.2	Effective force and translational momentum . . . . .	113
12.6	Moment of effective force of a particle . . . . .	113
12.6.1	Moment of effective force of a system of particles . . . . .	113
12.6.2	Shift theorem for moment of an effective force . . . . .	114
12.6.3	Moment of effective force and angular momentum . . . . .	114
12.7	Parallels between momentum and effective force . . . . .	114
12.8	Infant on a swing: Momentum, effective force, and energy . . . . .	115
12.9	Forming and solving $\vec{\mathbf{F}} = m\vec{\mathbf{a}}$ for translational motion . . . . .	116
12.10	Example: Velocity, acceleration, and $\vec{\mathbf{F}} = m\vec{\mathbf{a}}$ . . . . .	117
12.11	Optional: Proofs for momentum and effective force . . . . .	118
12.11.1	Proof of translational momentum of a system of particles . . . . .	118
12.11.2	Proof of effective force and its relationship to translational momentum . . . . .	118
12.11.3	Proof of shift theorem for angular momentum . . . . .	119
12.12	Optional: A different definition of angular momentum . . . . .	119
<b>13</b>	<b>Mass, center of mass, centroid</b> . . . . .	<b>121</b>
13.1	Mass . . . . .	121
13.2	Center of mass and centroid . . . . .	121
13.3	Figures and their length, area, and volume . . . . .	123
13.4	Integrals for mass, center of mass, and centroid . . . . .	123
13.5	Experiments, tables, CAD/CAE, and medical scanning . . . . .	124
13.6	Optional: Measuring mass . . . . .	124
13.7	Optional: The language and etymology of “mass” . . . . .	125
13.8	Optional: What is mass? . . . . .	125
13.9	Optional: Mass, energy, and physics . . . . .	125
<b>14</b>	<b>Concepts: Moments/products of inertia</b> . . . . .	<b>127</b>
14.1	Moment of inertia (also see Section 16.4) . . . . .	127
14.1.1	Example: Moments of inertia of a particle . . . . .	128
14.1.2	Conceptual example of moments of inertia . . . . .	128
14.1.3	Demonstration: Effect of moment of inertia on a rolling cylinder . . . . .	128
14.1.4	Demonstration: Effect of moment of inertia on a spinning book . . . . .	128
14.1.5	Shift theorem for moment of inertia (parallel axis theorem) . . . . .	129
14.2	Products of inertia (also see Section 16.5) . . . . .	129
14.2.1	Example: Products of inertia of a particle . . . . .	130
14.2.2	Conceptual example of products of inertia (also see Homework 12.6) . . . . .	130
14.2.3	Demo: Effect of product of inertia on a rattleback (wobblestone) . . . . .	130
14.2.4	Shift theorem for product of inertia . . . . .	131
14.2.5	Differences in opinion about product of inertia . . . . .	131
14.3	Optional: Radius of gyration and moment of inertia . . . . .	132
14.3.1	Concept: Radius of gyration as matter concentrated in a thin-ring . . . . .	132
14.3.2	Concept: Radius of gyration as a single particle . . . . .	132
14.3.3	Context: Uses for radius of gyration . . . . .	132
14.3.4	Calculation: Shift theorem for radius of gyration (parallel axis theorem) . . . . .	132
<b>15</b>	<b>Dyadics</b> . . . . .	<b>133</b>
15.1	Dyads, dyadics, and properties (vector * vector, dot-products, zero and unit dyadics) . . . . .	134
15.2	Dyadics and matrices . . . . .	135
15.3	Dyadic symmetry . . . . .	135
15.4	Dyadic principal directions, eigenvalues, and eigenvectors . . . . .	136
15.5	Optional: Dyadic inverse and positive-definite . . . . .	136
15.6	Optional: Proof of unit dyadic expressed in orthogonal basis . . . . .	136

<b>16 Inertia dyadics</b>	<b>137</b>
16.1 Inertia dyadics: A “suitcase” for moments and products of inertia . . . . .	137
16.1.1 Inertia dyadic for a particle . . . . .	137
16.1.2 Shift theorem for inertia dyadic . . . . .	137
16.1.3 Example: Inertia dyadic for an infant (particle) on a swing . . . . .	138
16.1.4 Example: Inertia dyadic of a particle . . . . .	138
16.1.5 Inertia dyadics for continuous systems . . . . .	139
16.2 Inertia matrix (a symmetric matrix) . . . . .	139
16.3 Inertia scalars . . . . .	140
16.4 Moments of inertia and inertia dyadics (also see Section 14.1) . . . . .	140
16.5 Products of inertia and inertia dyadics (also see Section 14.2) . . . . .	140
16.6 Example: Moments/products of inertia for an infant on a swing . . . . .	141
16.7 Example: Mass properties of three particles on a parallelepiped . . . . .	141
16.8 Optional: Axis-symmetric and triaxially-symmetric inertia . . . . .	142
16.9 Motivating concepts for inertia dyadics . . . . .	143
16.10 Inertia vector . . . . .	144
16.11 Principal inertia directions – an eigen-problem . . . . .	144
16.12 Optional: Summations and the inertia dyadic . . . . .	145
<b>17 Rigid bodies</b>	<b>147</b>
17.1 What is a rigid body? (see examples in Hw 14) . . . . .	147
17.2 Angular momentum of a rigid body $B$ about a point <u>fixed</u> on $B$ . . . . .	148
17.2.1 Angular momentum for a rigid body with simple angular velocity (2D) . . . . .	148
17.2.2 Reminder: Shift theorem for angular momentum of a rigid or flexible body $B$ . . . . .	148
17.2.3 Conservation of angular momentum for an axis-symmetric rigid body . . . . .	149
17.3 Effective force of a rigid or flexible body . . . . .	149
17.4 Moment of effective force of a rigid body . . . . .	149
17.5 Kinetic energy of a rigid body . . . . .	150
17.5.1 Kinetic energy special case: When point $B_p$ is $B_{cm}$ . . . . .	150
17.5.2 Kinetic energy of a rigid body with simple angular velocity (2D) . . . . .	151
17.6 Examples with an airplane (simple model) . . . . .	151
17.6.1 Translational momentum and angular momentum of an airplane in $N$ . . . . .	151
17.6.2 Effective force and moment of effective force of an airplane in $N$ . . . . .	151
17.6.3 Kinetic energy of an airplane ( $B$ 's kinetic energy in $N$ ) . . . . .	152
17.7 Optional: Proof of angular momentum for a rigid body $B$ . . . . .	152
17.8 Optional: Proof of moment of effective force for a rigid body . . . . .	153
17.9 Optional: Proof of kinetic energy for a rigid body . . . . .	155
17.10 Optional: Proof of conservation of angular momentum for an axis-symmetric rigid body . . . . .	156
<b>18 Force and resultant</b>	<b>157</b>
18.1 Force and the law of action/reaction . . . . .	157
18.2 Resultant of a set of vectors (e.g., forces on a point, body, or system) . . . . .	158
18.3 Resultant force on a system (internal force cancellation) . . . . .	158
18.4 Statics, dynamics, and resultant forces . . . . .	158
18.5 Force and effective force – two types of forces in $\vec{F} = m\vec{a}$ . . . . .	159
18.6 Contact and distance forces . . . . .	159
18.7 Applied and constraint forces . . . . .	159
18.8 Optional: Conditions for force to exist (section under ongoing discussion) . . . . .	159
18.9 Optional: The definition and philosophy of force . . . . .	160
18.10 Optional: Force, mass, gravity, space, time, reference frames . . . . .	160
18.11 Optional: Physicist’s fundamental forces . . . . .	161

<b>19 Moments and torque</b>	<b>163</b>
19.1 Moment of a vector . . . . .	163
19.1.1 Moment of a set of vectors . . . . .	163
19.1.2 Shift theorem for the moment of a set of vectors . . . . .	163
19.1.3 $\hat{\mathbf{u}} \cdot \vec{\mathbf{M}}^{S/P} = \hat{\mathbf{u}} \cdot \vec{\mathbf{M}}^{S/O}$ if $\hat{\mathbf{u}}$ is parallel to line $\overline{OP}$ (useful for MG road-maps in Section 22.6)	164
19.1.4 Moment arm of a vector about a point (example at end of Section 19.6) . . . . .	164
19.2 Moment of internal forces . . . . .	164
19.3 Statics, dynamics, and moments of forces . . . . .	164
19.4 Definition of static equilibrium . . . . .	165
19.5 Torque of a set of vectors (moment of a couple) . . . . .	165
19.5.1 Example: Torque – a special moment (moment of a couple) . . . . .	165
19.5.2 Torque on a rigid body (or reference frame) – getting practical . . . . .	165
19.6 Neuromuscular biomechanics example: Muscle tension for curling . . . . .	166
19.7 Optional: Proof of shift theorem for moment of a set of vectors . . . . .	168
19.8 Optional: Minimum moment magnitude/location (wrench) . . . . .	168
<b>20 Replacement of forces and bound vectors</b>	<b>169</b>
20.1 Replacement of distance forces (not a unique process) . . . . .	169
20.2 Replacement of contact forces . . . . .	170
20.3 Equivalence, replacement, and flexible bodies . . . . .	170
20.4 Replacement of forces associated with constraints . . . . .	171
20.5 Optional: Proof of action/reaction for contact forces . . . . .	172
<b>21 Encyclopedia of applied force and torque</b>	<b>173</b>
21.1 Weight, mass, and gravity . . . . .	173
21.2 Uniform gravity on a particle or body (see appendix for $g$ for planets) . . . . .	173
21.3 Universal gravitational attraction between two particles . . . . .	174
21.4 Electrostatic forces and Coulomb’s law for charged particles . . . . .	175
21.5 DC (direct current) permanent magnet motors . . . . .	175
21.6 Kinetic friction and the Continuous Friction Law . . . . .	176
21.7 Translational spring between two points . . . . .	177
21.8 Rotational (torsional) spring . . . . .	177
21.9 Translational damper between two points . . . . .	178
21.10 Rotational (torsional) damper . . . . .	178
21.11 Light linear springs and dampers in <i>series</i> . . . . .	179
21.12 Light linear springs and dampers in <i>parallel</i> . . . . .	179
21.13 Viscous damper between two surfaces . . . . .	180
21.14 Fluid forces (lift and drag) . . . . .	180
21.14.1 Demo: Experimental determination of drag forces on a coffee filter . . . . .	181
21.14.2 Closed-form solutions with aerodynamic drag . . . . .	181
21.15 Aerodynamic forces on a baseball - a case study in philosophy . . . . .	182
21.15.1 Drag force on a baseball having magnitude $b\vec{\mathbf{v}}_{\text{rel}}^2$ . . . . .	182
21.15.2 Lift (Magnus) force on a baseball . . . . .	183
21.15.3 Aerodynamic torque on a baseball . . . . .	184
21.15.4 Differences in aerodynamic models . . . . .	184
21.16 Optional: Gravitational attraction between a particle and a body . . . . .	185
21.17 Optional: Gravitational attraction between two bodies . . . . .	186
21.18 Optional: Center of gravity . . . . .	187
21.19 Optional: Proofs for spring and gravity forces . . . . .	188
21.19.1 Optional: Proof of light linear springs and dampers in <i>series</i> . . . . .	188
21.19.2 Optional: Proof of light linear springs and dampers in <i>parallel</i> . . . . .	188



21.19.3 Optional: Proof for uniform gravity on a body or set of particles . . . . .	188
<b>22 Dynamics: Laws of motion</b>	<b>189</b>
22.1 Newton’s law of motion for a particle . . . . .	190
22.2 Newton’s equation for a system . . . . .	190
22.3 Translational momentum principle . . . . .	190
22.4 Angular momentum principle . . . . .	190
22.5 Euler’s equations for a rigid body (3D) . . . . .	191
22.6 MG road-maps for efficient statics and dynamics . . . . .	192
22.6.1 MG road-map: Classic particle pendulum . . . . .	193
22.6.2 MG road-map: Inverted pendulum on cart ( $x$ and $\theta$ ) . . . . .	193
22.6.3 MG road-map: Particle on spinning slot . . . . .	193
22.7 Impulse/momentum . . . . .	194
22.8 Conservation of momentum . . . . .	194
22.9 Optional: Proof: Translational momentum principle ( $\vec{\mathbf{F}}^S = m^S * {}^N\vec{\mathbf{a}}^{S_{cm}}$ ) . . . . .	195
22.10 Proof: Angular momentum principle, Euler’s rigid body equation . . . . .	195
<b>23 Power and work</b>	<b>199</b>
23.1 Power/energy-rate principle (for any system $S$ in a Newtonian frame $N$ ). . . . .	199
23.1.1 Rotational power/energy-rate principle for a rigid body . . . . .	200
23.1.2 Translational power/energy-rate principle . . . . .	201
23.2 Power of a force, set of forces, or torque on a rigid body . . . . .	201
23.3 Forces that do not contribute to power (workless forces) . . . . .	202
23.4 Power/energy-rate to size a torque-motor . . . . .	202
23.5 Power/energy-rate for a commercial spring scale . . . . .	203
23.6 Definition of work with an integral or differential equation . . . . .	204
23.7 Work/energy principle . . . . .	204
23.8 Optional: Proofs with power . . . . .	205
23.8.1 Optional: Proof of the power/energy-rate principle . . . . .	205
23.8.2 Optional: Proof of the rotational power/energy-rate principle . . . . .	205
23.8.3 Optional: Proof of the translational power/energy-rate principle . . . . .	206
23.8.4 Optional: Proof for power of a set of forces (or <u>torque</u> ) on a rigid body $B$ . . . . .	206
<b>24 Potential energy</b>	<b>207</b>
24.1 Work/Energy principle . . . . .	207
24.2 Conservation of mechanical energy (special case of work/energy) . . . . .	207
24.3 Potential energy - a special type of work for “conservative” forces . . . . .	208
24.3.1 Potential energy for a constant force or a uniform gravitational field . . . . .	208
24.3.2 Potential energy for central forces (e.g., springs and inverse-square-law gravity) . . . . .	209
24.3.3 Potential energy for a simple rotational spring . . . . .	209
24.4 Force and gradient of potential energy . . . . .	210
24.5 Optional: Proofs of potential energy . . . . .	210
24.5.1 Optional: Proof of potential energy for a constant force in reference frame $N$ . . . . .	210
24.5.2 Optional: Proof of potential energy for a central force . . . . .	210
24.5.3 Optional: Proof of applied force as negative gradient of potential energy . . . . .	211
<b>25 Kane’s method</b>	<b>213</b>
25.1 Kane’s equation of motion (dynamics) . . . . .	213
25.1.1 Examples of Kane’s method (also see examples in Hw 20, 21) . . . . .	213
25.1.2 Comparison of the methods of Kane and Lagrange (also see Section 27.8) . . . . .	213
25.2 Generalized speeds and partial velocities (for Kane’s method) . . . . .	214
25.3 Kane’s method (with proof) . . . . .	215

25.4	Generalized force - useful for Lagrange and Kane's equations . . . . .	216
25.4.1	Generalized force for a force, set of forces, or torque on a rigid body . . . . .	216
25.4.2	Generalized forces, potential energy, and statics (for a Newtonian reference frame $N$ ) . . . . .	217
25.4.3	Non-contributing forces (forces that do not contribute to generalized force) . . . . .	217
25.4.4	Example: Generalized force for a commercial spring scale . . . . .	217
25.4.5	Examples of generalized forces – also see guided problems in Hw 20, 21 . . . . .	217
25.5	Generalized effective force of a particle (handling $m\vec{a}$ ) . . . . .	218
25.5.1	Example of generalized effective force of a particle (refers to example in Section 12.8) . . . . .	218
25.5.2	Generalized effective force of a system of particles (handling $m\vec{a}$ ) . . . . .	218
25.6	Generalized effective force of a rigid body (handling $m\vec{a}$ and $I\vec{\alpha}$ ) . . . . .	218
25.6.1	Optional: Generalized effective force's relationship to kinetic energy . . . . .	219
25.6.2	Optional: Efficiency of generalized effective force vs. kinetic energy . . . . .	219
25.7	Optional: Generalized momentum of a particle and rigid body . . . . .	220
25.7.1	Generalized momentum of a system of particles . . . . .	220
25.7.2	Generalized momentum and kinetic energy for a system . . . . .	220
25.7.3	Example of generalized momentum of a particle . . . . .	220
25.7.4	Generalized momentum of a rigid body . . . . .	220
25.8	Optional: Proof of generalized effective force for a rigid body . . . . .	221
25.8.1	Optional: Proof of generalized forces from potential energy . . . . .	222
<b>26</b>	<b>Lagrange's equation of motion</b>	<b>223</b>
26.1	Lagrange's equations of the first and second kind . . . . .	223
26.1.1	Lagrange's equations - a mathematical process . . . . .	223
26.1.2	Examples of Lagrange's method (also see examples in Hw 20 ,21) . . . . .	223
26.1.3	Optional: Lagrange multipliers $\lambda$ . . . . .	223
26.2	Optional: Proof of Lagrange's equations of motion . . . . .	224
26.3	Optional: Virtual work . . . . .	226
26.3.1	Virtual work for a force or set of forces . . . . .	226
26.3.2	Virtual work of a set of forces (or torque) on a rigid body . . . . .	226
26.3.3	Virtual work and generalized force . . . . .	226
26.3.4	Virtual work and static equilibrium . . . . .	226
26.4	Optional: Virtual displacements/angular displacements . . . . .	227
26.5	Optional: Inefficiencies in Lagrange's equations . . . . .	227
26.6	Optional: Interchange property of partial/ordinary derivatives . . . . .	228
<b>27</b>	<b>Force and motion scalars: Generalized coordinates/speeds, . . .</b>	<b>229</b>
27.1	Force and impulse scalars - pushes and pulls . . . . .	229
27.2	State and state variables . . . . .	229
27.3	Position scalars and generalized coordinates . . . . .	229
27.4	Velocity scalars and generalized speeds (also see Section 27.8) . . . . .	230
27.5	Kinematical differential equations (ODEs) . . . . .	230
27.6	Velocity written in terms of velocity scalars (unconstrained) . . . . .	231
27.6.1	Velocity scalars, motion constraints, and degrees of freedom . . . . .	231
27.6.2	Optional: Motion constraints and independent/dependent velocity scalars . . . . .	231
27.6.3	Optional: Velocity written in terms of velocity scalars (with constraints) . . . . .	232
27.7	Research topic: Acceleration scalars . . . . .	232
27.8	Optional: Guidelines for choosing efficient velocity scalars . . . . .	233

<b>28 MIPSI: Classic particle pendulum</b>	<b>237</b>
28.1 Modeling the classic particle pendulum . . . . .	237
28.2 Identifiers for the classic particle pendulum . . . . .	238
28.3 Physics: Equations of motion of the classic particle pendulum . . . . .	238
28.3.1 $\vec{F} = m\vec{a}$ for the classic particle pendulum . . . . .	239
28.3.2 Angular momentum principle for the classic particle pendulum . . . . .	240
28.3.3 Euler’s rigid body equation for the classic particle pendulum . . . . .	240
28.3.4 Kinetic energy for the classic particle pendulum . . . . .	240
28.3.5 Power/energy-rate principle for the classic particle pendulum . . . . .	241
28.3.6 Conservation of mechanical energy for the classic particle pendulum . . . . .	241
28.3.7 Kane’s method for the classic particle pendulum . . . . .	242
28.3.8 Lagrange’s method for the classic particle pendulum . . . . .	242
28.4 Solution of the classic particle pendulum ODE . . . . .	242
28.4.1 Numerical solution of pendulum ODE via <b>MotionGenesis</b> and/or <b>MATLAB</b> <sup>®</sup> . . . . .	242
28.4.2 Analytical (closed-form) solution of the classic particle pendulum ODE . . . . .	243
28.4.3 Simplification and analytical solution of the classic particle pendulum ODE . . . . .	243
28.5 Interpretation of results for the classic particle pendulum . . . . .	243
<b>29 Example: Inverted pendulum on a cart</b>	<b>245</b>
29.1 Kinematics (space and time) . . . . .	245
29.2 Rotation matrix . . . . .	246
29.3 Angular velocity (special 2D case) . . . . .	246
29.4 Angular acceleration . . . . .	246
29.5 Position vectors (inspection and vector addition) . . . . .	246
29.6 Velocity and acceleration . . . . .	247
29.7 Forces, moments, and free-body diagrams (2D) . . . . .	247
29.8 Mass, center of mass, inertia (required by dynamics) . . . . .	248
29.9 Newton/Euler laws of motion for <i>A</i> and <i>B</i> separately (inefficient) . . . . .	248
29.9.1 Dynamics for a rigid body with a simple angular velocity (special 2D case) . . . . .	248
29.9.2 Optional: Angular momentum principle (2D alternative to Section 29.9.1) . . . . .	248
29.9.3 Optional: Angular momentum principle (3D alternative to Section 29.9.1) . . . . .	249
29.10 Equations of motion via MG road-maps/D’Alembert (efficient) . . . . .	249
29.11 Generalized forces for Lagrange/Kane’s equations of motion . . . . .	250
29.12 Lagrange’s equations of motion (described in Chapter 26) . . . . .	250
29.13 Kane’s equations of motion (described in Chapter 25) . . . . .	251
29.14 Matrix form of equations of motion (for solution, controls, . . .) . . . . .	251
<b>30 Solving for forces and motion. Forward, inverse, and mixed dynamics.</b>	<b>253</b>
30.1 Matrix form of equations of motion . . . . .	253
30.1.1 Inverse dynamics: Calculating knee joint torque . . . . .	254
30.1.2 Inverse dynamics: Calculating hip and knee joint torque . . . . .	254
30.2 Solving for forces and motion with operational tasks . . . . .	255
30.2.1 Inverse dynamics: Calculating forces from specified end-effector motion . . . . .	255
30.2.2 Inverse dynamics with operational task: Hip and knee joint torques . . . . .	256
<b>31 Feed-forward control</b>	<b>257</b>
31.1 Feed-forward control for directly controlling <i>Q</i> or <i>U</i> . . . . .	257
31.1.1 Example: Feed-forward control of a rocket sled’s <u>velocity</u> . . . . .	258
31.1.2 Example: Feed-forward control of rocket sled’s <u>position</u> . . . . .	259
31.1.3 Example: Feed-forward control with additional actuator . . . . .	260
31.2 Feed-forward control with operational tasks . . . . .	261
31.3 Optional: $k_p$ , $k_d$ , and analytical solutions of second-order ODEs . . . . .	262

31.4 Derivation/insights into the mathematics of feed-forward control . . . . .	263
<b>32 Flexible Bodies (Overview)</b> . . . . .	<b>265</b>
32.1 Three points associated with flexible-body motion . . . . .	265
32.2 References for Banerjee's flexible-body theory . . . . .	265
Appendix: Mass and geometry properties of common objects . . . . .	267
<b>Appendices and index</b> . . . . .	<b>267</b>
Appendix of constants . . . . .	272
Rotation tables and the angle $\theta$ . . . . .	273
Rotation tables and angles $\theta_1$ and $\theta_2$ . . . . .	274
Rotation tables and angles $\theta_1, \theta_2, \theta_3$ . . . . .	276
Summary of equations . . . . .	279
Bibliography . . . . .	285
<b>Homework</b> . . . . .	<b>289</b>
Homework 1: Vectors (basis independent) . . . . .	291
Homework 2: Vector addition and dot/cross-products (with basis) . . . . .	297
Homework 3: Position vectors and geometry . . . . .	305
Homework 4: Vector bases and rotation matrices I . . . . .	313
Homework 5: Vector differentiation . . . . .	323
Homework 6: Angular velocity and angular acceleration . . . . .	333
Homework 7: Vector bases and rotation matrices II . . . . .	345
Homework 8: Velocity and acceleration I . . . . .	353
Homework 9: Velocity and acceleration II . . . . .	367
Homework 10: Constraints . . . . .	377
Homework 11: Particle mass, translational/angular momentum, kinetic energy, etc. . . . .	399
Homework 12: Moments and products of inertia, dynamic Celt (rattleback) . . . . .	415
Homework 13: Inertia dyadics . . . . .	427
Homework 14: Rigid bodies translational/angular momentum, kinetic energy, etc. . . . .	435
Homework 15: Forces, force models, and statics . . . . .	449
Homework 16: Moments and static equilibrium . . . . .	455
Homework 17: $\vec{F} = m\vec{a}$ and FBDs for translating mechanical systems . . . . .	469
Homework 18: $\vec{M} = \frac{d\vec{H}}{dt}$ and FBDs for rotating rigid bodies . . . . .	475
Homework 19: Power, work, and potential energy . . . . .	487
Homework 20: Kane/Lagrange dynamics (unconstrained) . . . . .	497
Homework 21: Kane/Lagrange dynamics (with constraints) . . . . .	507
Homework 22: Dynamics with control . . . . .	523
Homework 23: MIPS simulation project . . . . .	525
Table of customizable notation at: <a href="http://www.MotionGenesis.com">www.MotionGenesis.com</a> $\Rightarrow$ Textbooks $\Rightarrow$ Resources . . . . .	i
Energy integrals and Hamiltonian at: <a href="http://www.MotionGenesis.com">www.MotionGenesis.com</a> $\Rightarrow$ Textbooks $\Rightarrow$ Resources . . . . .	i