

Contents

Statics and dynamics – what does it do for us?	i
Newton’s three laws	ii
1 Math tools	1
1.1 Unit systems - SI and USA	1
1.2 Geometry: Ancient Euclid and modern vectors (see Chapters 2, 3, ...).	2
1.3 Circles and their properties	2
1.4 Triangles and ratios of their sides (sine, cosine, tangent)	2
1.4.1 Unit circle concept of sine and cosine	2
1.4.2 Formulas involving sine and cosine	3
1.4.3 Sine and cosine as functions (Euler, circa 1730)	3
1.5 Types of scalars: Variable, specified, constant	3
1.6 Differentiation	4
1.6.1 Definition of an ordinary derivative of a scalar function	4
1.6.2 Definition of a partial derivative of a scalar function	4
1.6.3 Definition of the total derivative of a scalar function (a better chain rule)	4
1.6.4 Short table of derivatives frequently encountered in engineering	5
1.6.5 Example: Partial and ordinary differentiation	5
1.6.6 Good product rule for differentiation (for scalars, $\vec{v}$ ectors, matrices, ...)	5
1.6.7 Quotient rule for derivatives (or remember $\frac{u}{v} = u v^{-1}$ and use exponent and product rules)	5
1.6.8 Chain rule for ordinary derivatives	5
1.6.9 Implicit differentiation: A useful tool for calculating derivatives	6
1.7 Integration and a short table of integrals	6
1.8 Solutions of <i>polynomial</i> equations (roots)quadratic equation	6
STATICS: $\sum \vec{F} = \vec{0}$ $\sum \vec{M} = \vec{0}$	7
2 Vectors ($\hat{=}$ = $-\vec{v}$ + $-$ * $\cdot$ $\vec{v}^2$ $\times$)	7
2.1 Examples of scalars vectors and dyadics	7
2.2 Definition of a vector	7
2.3 Zero vector $\vec{0}$, a vector whose magnitude is zero	8
2.4 Unit $\hat{v}$ ectors: Vectors with magnitude 1 and no units (typeset with a $\hat{h}$ at)	8
2.5 Equal vectors (=) vectors with the same magnitude and direction	8
2.6 Vector addition (+)	9
2.7 Vector multiplied or divided by a scalar (* or /)	9
2.8 Vector negation and subtraction (-)	9
2.9 Vector dot product ($\cdot$)	10
2.9.1 Properties of the dot-product ($\cdot$)	10
2.9.2 Uses for the dot-product ($\cdot$)	10
2.9.3 Dot-products to change vector equations to scalar equations (see Hw 1.28)	10

2.9.4	Special case: Dot-products with orthogonal unit vectors	10
2.9.5	Examples: Vector dot-products ($\cdot$)	11
2.10	Vector cross product ($\times$)	11
2.10.1	Uses for the cross-product ($\times$) in geometry, statics, motion analysis,	11
2.10.2	Determinants and cross-products (with right-handed unit vectors)	12
2.11	Optional: Scalar triple product ($\cdot \times$ or $\times \cdot$)	12
2.11.1	Scalar triple product and the volume of a tetrahedron	12
2.11.2	($\times \cdot$) to change vector equations to scalar equations (see Hw 1.28)	12
3	Position vectors and vector geometry	13
3.1	Position of a point (or particle) (see examples in Hw 3)	13
3.2	Distance between a point and a line	13
3.3	Area of a triangle	14
3.4	Geometry example: Length/distances, angle, surface area, volume	14
4	Vector basis	15
4.1	What is a vector basis?	15
4.2	Expressing a vector in terms of the basis $\vec{a}_1, \vec{a}_2, \vec{a}_3$	15
4.3	Concept: What is the vector vs. how is it expressed	16
5	Rotation matrices (resolving unit vectors into components)	17
5.1	Uses for the rotation matrix ${}^aR^b$ (for geometry, statics, motion analysis, stress ...)	17
5.2	Examples of how to use a rotation matrix	18
5.2.1	Example: Calculating angles between unit vectors $\hat{a}_x, \hat{a}_y, \hat{a}_z$ and $\hat{b}_x, \hat{b}_y, \hat{b}_z$	18
5.2.2	Example: Calculation of rotation matrix inverse (for efficiency, use the transpose). . . .	18
5.2.3	Example: Rotation matrix for express, dot, and cross	18
5.3	Simple rotation matrices	19
5.3.1	Example: Forming the simple rotation matrix ${}^aR^n$	19
5.3.2	Example: Forming the simple rotation matrix ${}^bR^a$	19
5.3.3	Hug rule (a pattern for quickly forming simple rotation matrices)	20
5.4	Forming rotation matrices with matrix multiplication	20
5.5	What is an angle?	21
6	Matrices and $AX = B$	23
6.1	Motivating question: Solving <u>one</u> linear algebraic equation	23
6.2	Why use matrices – getting organized	23
6.3	What is a matrix?	23
6.4	Row and column matrices	24
6.5	Addition of matrices	24
6.6	Multiplication of a matrix with a scalar	24
6.7	Multiplication of matrices	24
6.8	The zero matrix and the identity matrix	24
6.9	Transpose of a matrix	25
6.10	Submatrices of a matrix	25
6.11	Determinant of a matrix, minors and cofactors	25
6.12	Adjugate matrix (or classical adjoint matrix)	26
6.13	Inverse of a matrix	26
6.14	Changing linear algebraic equations into matrix form $AX = B$	27
6.15	Solving the matrix linear algebraic equation $AX = B$	27
6.16	Optional: Pseudo-inverse solutions to $AX = B$	27
6.17	Partial and ordinary derivative of a matrix	28
6.18	Optional: Other matrices and their properties	28

7	Eigenvalues and eigenvectors	29
7.1	Recognize and remember: Solving an eigenvalue problem	29
7.2	Motivating questions for eigenvalues and eigenvectors (Hw 5.9)	29
7.3	Solving the standard algebraic eigenvalue problem	31
7.3.1	Special eigenvalues for the $n \times n$ matrix A	31
7.3.2	Eigenvalues and the roots of a polynomial	31
7.4	Situations when $\text{Matrix}(\lambda)$ is nonlinear in λ	32
7.5	Optional: Generalized eigenvalue problem	33
8	Mass, center of mass, centroid	35
8.1	Mass	35
8.2	Center of mass and centroid	35
8.3	Optional: Figures and their length, area, and volume	37
8.4	Optional: Integrals for mass, center of mass, and centroid	37
8.5	Optional: Experiments, tables, CAD/CAE, and medical scanning	38
8.6	Optional: Measuring mass	38
8.7	Optional: The language and etymology of “mass”	38
8.8	Optional: What is mass?	38
9	Force and resultant	39
9.1	Force and the law of action/reaction	39
9.2	Statics, dynamics, and resultant forces	40
9.3	Resultant of a set of vectors (e.g., forces on a point, body, or system)	40
9.4	Resultant force on a system (internal force cancellation)	40
9.5	Contact and distance forces	41
9.6	Applied and constraint forces	41
9.7	Optional: The definition and philosophy of force	41
10	Moment and torque	43
10.1	Moment of a vector	43
10.1.1	Moment of a set of vectors	43
10.1.2	Shift theorem for the moment of a set of vectors	43
10.1.3	$\hat{\mathbf{u}} \cdot \vec{\mathbf{M}}_{S/P} = \hat{\mathbf{u}} \cdot \vec{\mathbf{M}}_{S/O}$ if $\hat{\mathbf{u}}$ is parallel to line $\overline{OP}$ (useful for MG road-maps in Section 23.1)	44
10.1.4	Moment arm of a vector about a point (example at end of Section 10.6)	44
10.2	Moment of internal forces (a separate law of mechanics?)	44
10.3	Statics, dynamics, and moments of forces	44
10.4	Definition of static equilibrium	44
10.5	Torque of a set of vectors (moment of a couple)	45
10.6	Neuromuscular biomechanics example: Muscle tension for curling	46
11	Replacement of forces and bound vectors	49
11.1	Replacement of distance forces (not a unique process)	49
11.2	Replacement of contact forces	50
11.3	Applicability of equivalence/replacement?	50
11.4	Replacement of forces associated with constraints	51
12	Encyclopedia of applied force and torque	53
12.1	Weight, mass, and gravity	53
12.2	Uniform gravity on a particle or body (see appendix for g for planets)	53
12.3	Universal gravitational attraction between two particles	54
12.4	Electrostatic forces and Coulomb’s law for charged particles	55
12.5	DC (direct current) permanent magnet motors	55

12.6 Kinetic friction and the Continuous Friction Law	56
12.7 Translational spring between two points	57
12.8 Rotational (torsional) spring	57
12.9 Translational damper between two points	58
12.10 Rotational (torsional) damper	58
12.11 Light linear springs and dampers in <i>series</i>	59
12.12 Light linear springs and dampers in <i>parallel</i>	59
12.13 Viscous damper between two surfaces	60
12.14 Fluid forces (lift and drag)	60
12.14.1 Demo: Experimental determination of drag forces on a coffee filter	61
12.14.2 Closed-form solutions with aerodynamic drag	61
12.15 Baseball aerodynamic lift/drag/torque - a case study in philosophy	62
12.16 Optional: Proofs for spring and gravity forces	65
12.16.1 Optional: Proof of light linear springs and dampers in <i>series</i>	65
12.16.2 Optional: Proof of light linear springs and dampers in <i>parallel</i>	65
12.16.3 Optional: Proof for uniform gravity on a body or set of particles	65

DYNAMICS: $\sum \vec{F} = m\vec{a}$ $\sum \vec{M} = \frac{d\vec{H}}{dt}$... 66

13 Vector differentiation 67

13.1 Definition: Derivative of a vector in a rigid basis (or reference frame)	67
13.2 What is a constant vector (i.e., a vector fixed in a reference frame).	67
13.3 Properties of derivatives of vectors	67
13.4 Example: Derivative of a vector	68
13.5 Differentiation concepts: Changes in magnitude and direction	68

14 Angular velocity & angular acceleration 69

14.1 Angular velocity concepts: Moon and Earth celestial systems	69
14.2 What is a reference frame or a Newtonian reference frame?	70
14.3 Angular velocity and the golden rule for vector differentiation	70
14.3.1 Example: Angular velocity and vector differentiation	70
14.3.2 Example: Vector differentiation and angular momentum – spinning body	71
14.3.3 Simple angular velocity	71
14.3.4 Angular velocity negative property	72
14.3.5 Angular velocity addition theorem (<i>squash rule for adding angular velocities</i>)	72
14.3.6 Angular velocity example: Welding robot	72
14.3.7 Angular velocity example: Chaotic plate pendulum	72
14.4 Angular acceleration	72
14.5 Optional: Angular velocity proofs	73
14.5.1 Proof of angular velocity and orthogonal basis vectors	73
14.5.2 Proof of simple angular velocity	73
14.5.3 Proof of angular velocity addition theorem	74
14.5.4 Proof of angular velocity negative property	74

15 Points: Velocity and acceleration 75

15.1 Definition of a point's velocity and acceleration	75
15.2 Velocity and acceleration of two points <u>fixed</u> on a rigid body	77
15.3 Relationship between position, velocity, and acceleration	78
15.3.1 Constant acceleration along a curve or line (also see Hw 14.9)	78
15.3.2 Circular motion and centripetal acceleration – a special case	78

15.3.3	Analogy between translational motion and planar (2D) rotational motion	78
15.3.4	Example: Free-fall of a sky-diver with constant downward acceleration	79
15.4	Speed and distance-traveled in a reference frame (see Hw 16.15)	79
15.5	Optional: Acceleration vocabulary	79
15.6	Optional: How g 's affect human health (biomechanics)	80
15.7	Optional: Velocity and acceleration proofs	80
16	Constraints: Rods, rolling, gears, . . .	81
16.1	Rods, ropes, and separators	81
16.2	Linear actuator	81
16.3	Ball and socket joint	82
16.4	Revolute joint (also called a hinge or pin joint)	82
16.5	Revolute motor (revolute joint with additional angular constraint)	82
16.6	Prismatic joint (also called a slider joint or square-slot joint)	82
16.7	Contact (an intermittent inequality constraint)	83
16.8	Sliding and rolling (a special type of contact)	83
16.9	Gears and constraint equations	84
17	Particles (points with mass)	87
17.1	Recipe for $\vec{F} = m\vec{a}$ (examples in Sections 17.8 and 17.9 and in Hw 16)	88
17.2	Systems with particles	88
17.3	Translational (linear) momentum for particles	88
17.4	Angular momentum and shift theorem for particles	89
17.5	Shift theorems for moments of momentum, force, inertia,	89
17.6	Kinetic energy for particles	90
17.7	Example: Momentum and energy for a child on a swing	91
17.8	Example: Recipe for $\vec{F} = m\vec{a}$ (rocket-sled)	92
17.9	Example: Recipe for $\vec{F} = m\vec{a}$ (particle in spinning slot)	93
17.10	Optional: Proofs for translational/angular momentum	94
17.10.1	Proof of translational momentum of a system of particles	94
17.10.2	Proof of shift theorem for angular momentum	94
18	Concepts: Moments/products of inertia	95
18.1	Moment of inertia (also see Section 20.2)	95
18.1.1	Shift theorem for moment of inertia (parallel axis theorem)	96
18.1.2	Example: Moments of inertia of a particle (repeated in Hw 17.2)	96
18.1.3	Example: Moment of inertia concepts (repeated in Hw 17.3)	96
18.1.4	Demo: How moment of inertia affects rolling objects	97
18.1.5	Demo: How moment of inertia affects a spinning book (repeated in Hw 17.4)	97
18.2	Products of inertia (also see Section 20.3)	97
18.2.1	Example: Products of inertia of a particle (repeated in Hw 17.2)	97
18.2.2	Conceptual example of products of inertia (repeated in Hw 17.9)	98
18.2.3	Demo: How product of inertia affects a rotating rattleback (repeated in Hw 17.18)	98
18.2.4	Optional: Two sign conventions ($\pm$) for products of inertia	98
19	Dyadics	99
19.1	Dyadics and 3×3 matrices	100
19.2	Dyadic symmetry	100

20 Inertia dyadics	101
20.1 Inertia dyadic: A “suitcase” for moments and products of inertia	101
20.1.1 Inertia dyadic for a particle or system	101
20.1.2 Shift theorem for an inertia dyadic (for an arbitrary system S)	101
20.1.3 Example: Inertia dyadic of a particle (also see example in Section 20.5)	102
20.2 Moments of inertia and inertia dyadics (also see Section 18.1)	102
20.3 Products of inertia and inertia dyadics (also see Section 18.2)	103
20.4 Inertia matrix (a symmetric matrix)	103
20.5 Example: Inertia properties for a child on a swing	104
20.6 Optional: Motivating concepts for inertia dyadics	105
21 Rigid bodies	107
21.1 What is a rigid body? (see examples in Hw 18, laws of motion in Chapter 22).	107
21.2 Angular momentum of a rigid body (also see Sections 22.4, 22.9)	108
21.3 Kinetic energy of a rigid body	109
21.4 Example: Momentum of an inverted pendulum on cart	110
21.5 Example: Momentum & kinetic energy (simplified aircraft)	110
21.6 Optional: Proof of angular momentum for a rigid body	111
21.7 Optional: Proof of kinetic energy for a rigid body	112
22 Newton/Euler dynamics	113
22.1 Newton’s law of motion for a particle	113
22.2 Newton’s equation for a system	113
22.3 Translational momentum principle	114
22.4 Angular momentum principle	114
22.5 Euler’s equation for a rigid body (2D) $\vec{M}_z = I_{zz} \vec{\alpha} + \dots$	114
22.6 Euler’s equations for a rigid body (3D)	115
22.7 Optional: Lagrange’s equations of the second kind	115
22.8 Impulse/momentum	115
22.9 Conservation of translational/angular momentum	116
22.10 Optional: Proof: Translational momentum principle	116
22.11 Optional: Proof: Angular momentum principle	117
23 Dynamics with MG road-maps (D’Alembert’s method)	119
23.1 MG road-maps for efficient statics and dynamics	120
23.1.1 MG road-map: Projectile motion (2D)	121
23.1.2 MG road-map: Rigid body pendulum (2D)	121
23.1.3 MG road-map: Inverted pendulum on cart (x and θ) (2D)	121
23.1.4 MG road-map: Rotating rigid body (3D)	122
23.1.5 MG road-map: Bridge crane equations of motion (2D)	122
23.1.6 MG road-map: Particle on spinning slot (2D)	122
23.1.7 MG road-map: Motion of a chaotic double pendulum (3D)	123
23.1.8 MG road-map: Particle pendulum (2D) – angle and tension	123
24 Power and work	125
24.1 Power/kinetic energy-rate principle	125
24.2 Forces that do not contribute to power (workless forces)	125
24.3 Why the power/kinetic energy-rate principle is such a useful tool.	126
24.4 Power of a force, set of forces, or torque on a rigid body	127
24.5 Example: Power/kinetic energy-rate to size a torque-motor	127
24.6 Power/kinetic energy-rate for a commercial spring scale	128
24.7 Definition of work with an integral or differential equation	129

24.8	Work/kinetic energy principle	129
24.9	Optional: Proofs with power	130
24.9.1	Optional: Proof of the power/kinetic energy-rate principle	130
24.9.2	Optional: Proof for power of a set of forces (or <u>torque</u>) on a rigid body B	130
25	Potential energy and energy conservation	131
25.1	Work/kinetic energy principle (summarized from Section 24.8)	131
25.2	Conservation of mechanical energy (special case of work/kinetic energy)	131
25.3	Potential energy - a special type of work for “conservative” forces	132
25.3.1	Potential energy for a constant force or a uniform gravitational field	132
25.3.2	Potential energy for central forces (e.g., springs and inverse-square-law gravity)	133
25.3.3	Potential energy for a simple rotational spring	133
25.4	Optional: Proofs of potential energy	134
25.4.1	Optional: Proof of potential energy for a constant force in reference frame N	134
25.4.2	Optional: Proof of potential energy for a central force	134
26	MIPSI: Classic particle pendulum	135
26.1	Modeling the classic particle pendulum	135
26.2	Identifiers for the classic particle pendulum	136
26.3	Physics: Equations of motion of the classic particle pendulum	136
26.3.1	$\vec{F} = m\vec{a}$ for the particle pendulum	137
26.3.2	Angular momentum principle for the particle pendulum	137
26.3.3	Euler’s rigid body equation for the particle pendulum	138
26.3.4	Kinetic energy for the particle pendulum	138
26.3.5	Power/kinetic energy-rate principle for the particle pendulum	138
26.3.6	Conservation of mechanical energy for the particle pendulum	139
26.3.7	Lagrange’s method for the particle pendulum	139
26.4	Solution of the classic particle pendulum ODE	139
26.4.1	Numerical solution of pendulum ODE via MotionGenesis and/or MATLAB [®]	139
26.4.2	Optional: Exact (closed-form) solution of the classic particle pendulum ODE	140
26.4.3	Simplification and analytical solution of the classic particle pendulum ODE	140
26.5	Interpretation of results for the classic particle pendulum	140
27	Example: Inverted pendulum on cart	141
27.1	Kinematics (space and time)	141
27.2	Rotation matrix, angular velocity, angular acceleration	141
27.3	Position vectors, velocity, acceleration	142
27.4	Forces, moments, and 2D free-body diagrams (FBD)	143
27.5	Mass, center of mass, inertia (required by dynamics)	143
27.6	Newton/Euler laws of motion for A and B separately (inefficient)	143
27.7	Dynamics of a rigid body with simple angular velocity (special 2D case)	144
27.8	Optional: Angular momentum principle (2D alternative to Section 27.7)	144
27.9	Equations of motion via MG road-maps/D’Alembert (efficient)	144
27.10	Matrix form of equations of motion (for solution, controls, . . .)	144
HOMEWORK		145
	Homework 1: Vectors (basis independent)	147
	Homework 2: Vector addition and dot/cross-products (with basis)	153
	Homework 3: Optional/Advanced: Position vectors and geometry	159
	Homework 4: Vector bases and rotation matrices	163
	Homework 5: Matrix algebra	175
	Homework 6: Forces and force models	179

Homework 7: Moments, torques, and static equilibrium	183
Homework 8: Two-force members, trusses, and statics	193
Homework 9: Moment, torque, and replacement	201
Homework 10: Systems and static equilibrium	205
Homework 11: Axial/shear force and bending moment diagrams	211
Homework 12: Vector differentiation (start of DYNAMICS)	217
Homework 13: Angular velocity and angular acceleration	225
Homework 14: Velocity and acceleration	235
Homework 15: Constraints	251
Homework 16: Particle mass, translational/angular momentum, kinetic energy, etc.	257
Homework 17: Moments and products of inertia, dynamic Celt (rattleback)	277
Homework 18: Rigid body: Momentum, energy, and equations of motion.	289
Homework 19: Advanced: $\vec{F} = m\vec{a}$ for translational motion (MG road-maps)	305
Homework 20: Advanced: $\vec{M} = \frac{d\vec{H}}{dt} + \dots$ for rotational motion (MG road-maps)	311
Homework 21: Optional: Power, work, potential energy, conservation of energy	325
Homework 22: Optional: MIPS simulation project	335
Appendices and index	337
Appendix: Mass and geometry properties of common objects	337
Appendix of constants	342
Summary of equations	343
Bibliography	347