SOLUTIONS MANUAL

MECHANICAL VIBRATIONS

SIXTH EDITION

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To Lord Sri Venkateswara

Preface

The MATLAB programs given in the book, answers to problems, and answers to review questions can be found on the Pearson Engineering Resources Portal: www.pearsonhighered.com/engineeringresources/.

The programs and techniques presented in the book and the solutions manual as well as the information provided at Pearson Engineering Resources Portal are intended for use by students in learning the material. Although the material has been tested, no warranty is implied as to their accuracy.

I would appreciate receiving any errors found in the book, solutions manual or at the Pearson Engineering Resources Portal of the book. The errors detected will be posted at the Pearson Engineering Resources Portal of the book.

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Contents

ERRATA (FOR TEXT BOOK)

Mechanical Vibrations Sixth Edition, Singiresu S. Rao

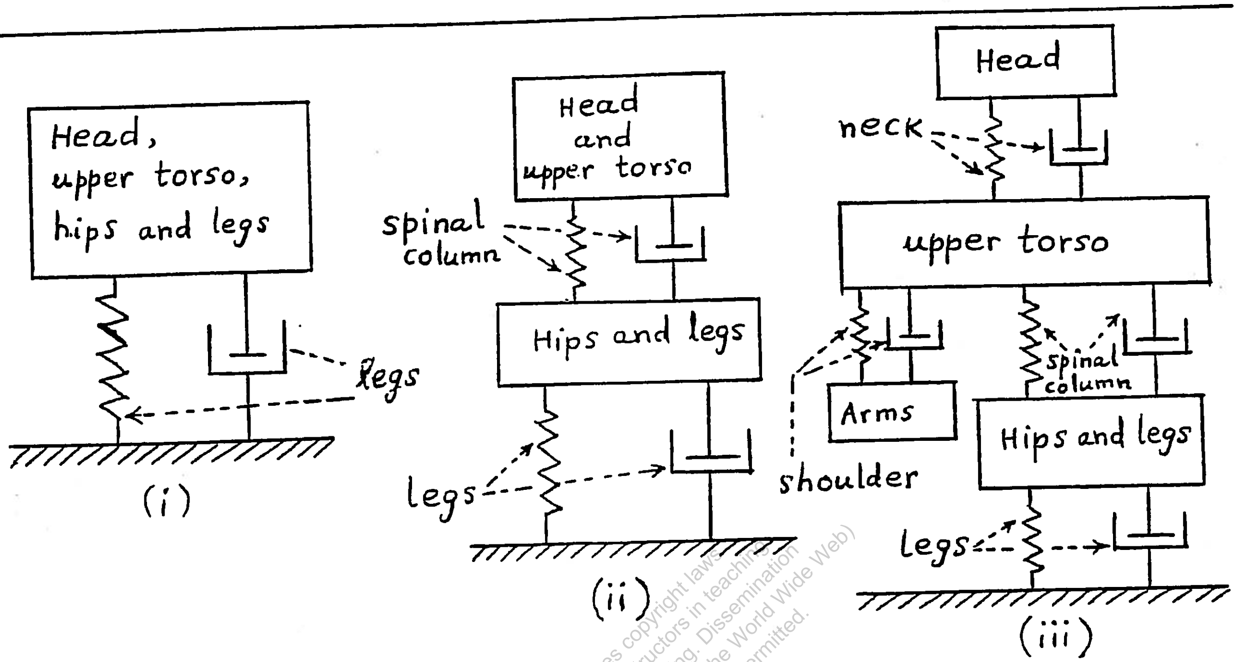
(January 10, 2016)

1. Page 238 Problems 2.55-2.58 line 3 change $k = 10{,}000$ to $k = 10{,}000$ N/m
2. Page 239 Problem 2.65 Replace (a) by the following:
   (a) Find whether the trunk of the tree will buckle under the weight of the crown of the tree assuming that the weight of the crown acts as an axial load at the top of the trunk. Assume the height of the trunk as $l = l_h = 10$ m.
3. Page 253 Problem 2.121 Add the following line after part (d):
   Assume $m = 10$ kg and $k = 10{,}000$ N/m.
4. Page 253 Problem 2.122 Add the following line after part (d):
   Assume $m = 10$ kg and $k = 10{,}000$ N/m.
5. Page 254 Problem 2.123 Add the following line after part (d):
   Assume $m = 10$ kg and $k = 10{,}000$ N/m.
6. Page 368 Problem 3.87 line 3 modify the end of the sentence as follows:
   Replace "respectively." by "respectively, and $\varepsilon = m / M$."

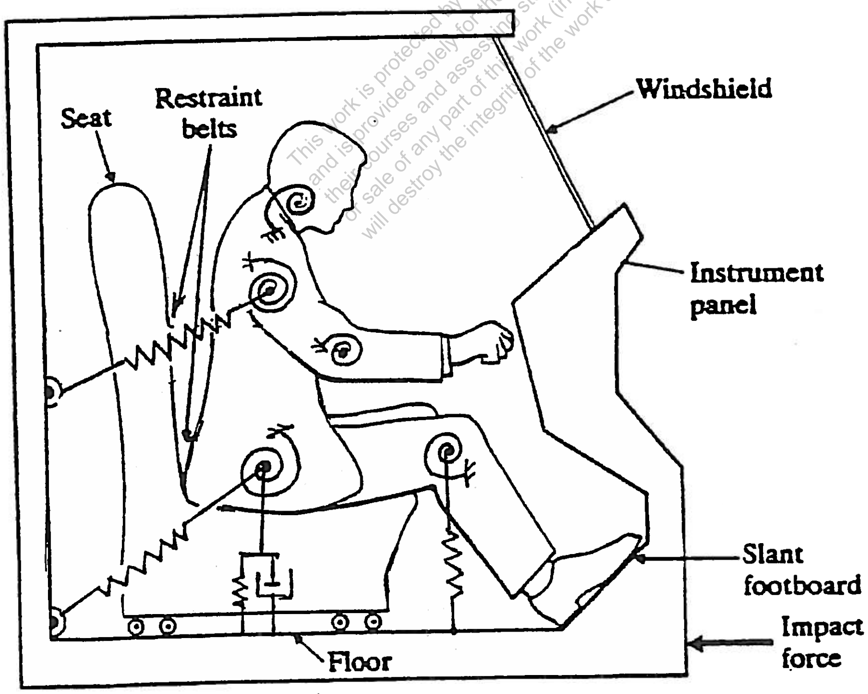
Chapter 1

Fundamentals of Vibration

1.1



1.2



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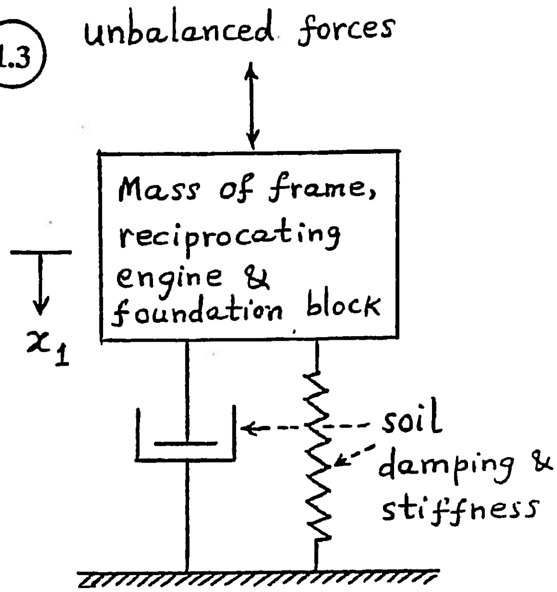
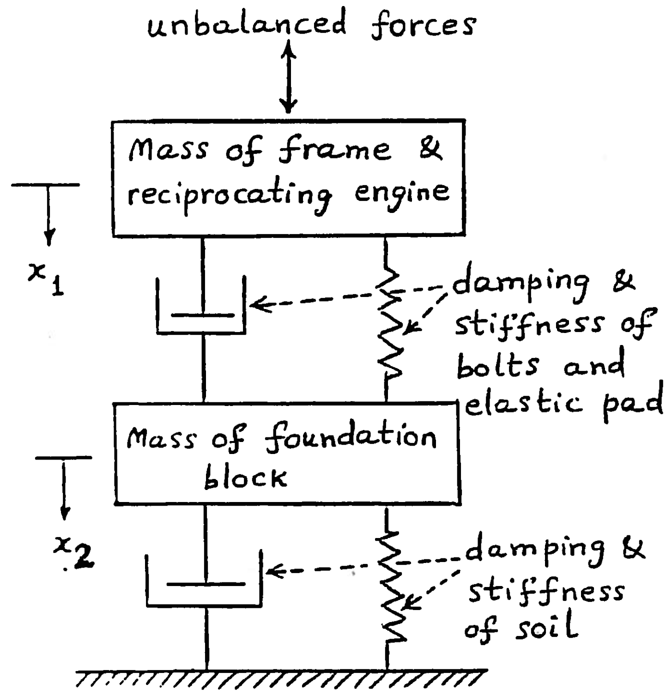
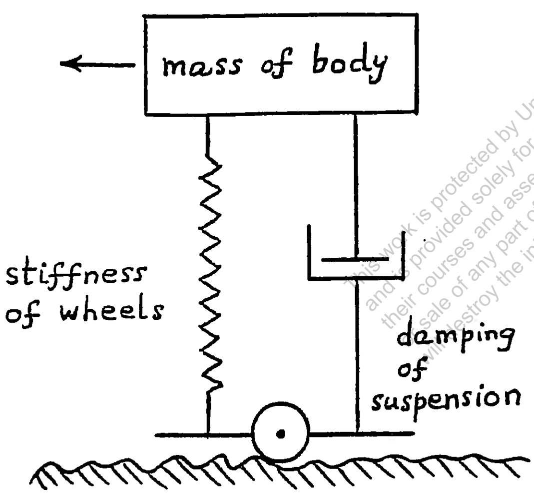


(a) one degree of freedom model

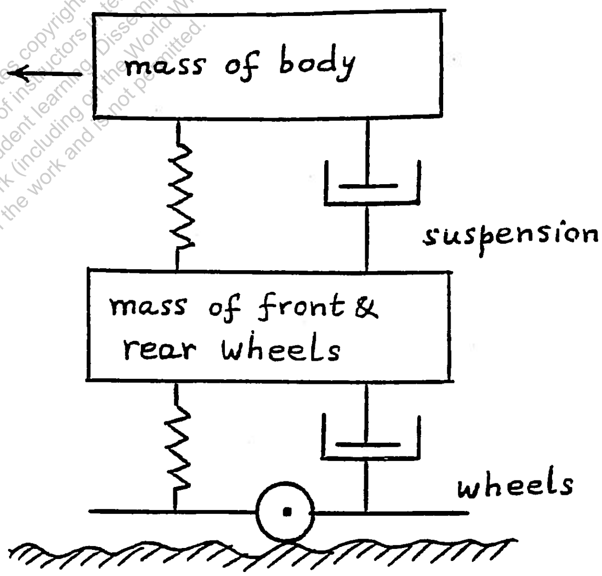


(b) Two degree of freedom model

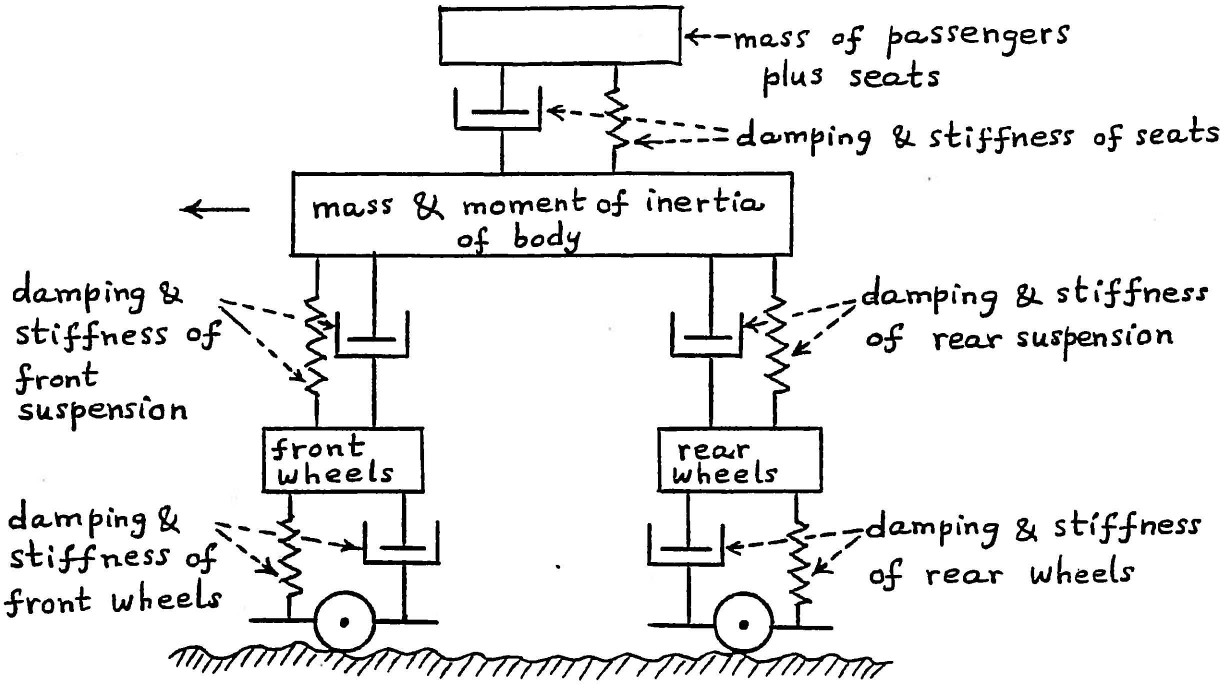
1.4



(i)

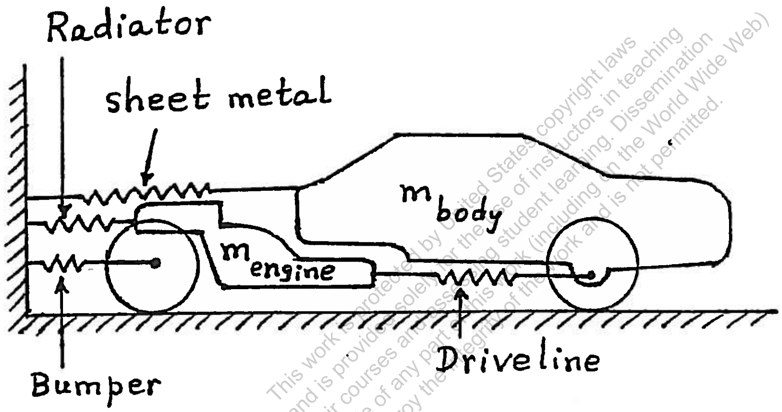


(ii)

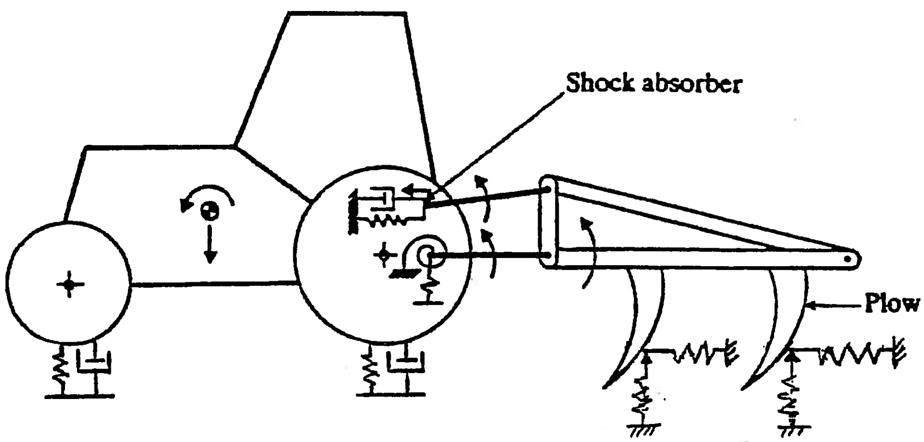

mass of passengers plus seats
damping & stiffness of seats
mass & moment of inertia of body
damping & stiffness of front suspension
damping & stiffness of rear suspension
front wheels
rear wheels
damping & stiffness of front wheels
damping & stiffness of rear wheels

(iii)

1.5

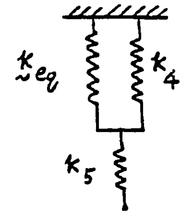

Radiator
sheet metal
m body
m engine
Bumper
Driveline

1.6


Shock absorber
Plow

1.7

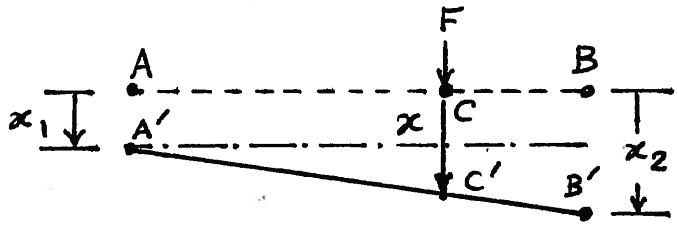
$$\frac{1}{\underset{\sim}{k}_{eq}} = \frac{1}{2k_1} + \frac{1}{k_2} + \frac{1}{2k_3} \quad ; \quad \underset{\sim}{k}_{eq} = \left(\frac{2k_1k_2k_3}{k_2k_3 + 2k_1k_3 + k_1k_2}\right)$$



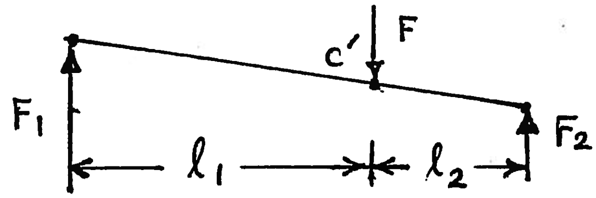
$$\frac{1}{k_{eq}} = \frac{1}{\underset{\sim}{k}_{eq} + k_4} + \frac{1}{k_5}$$

$$k_{eq} = \frac{k_5(\underset{\sim}{k}_{eq} + k_4)}{k_5 + k_4 + \underset{\sim}{k}_{eq}} = \frac{k_2k_3k_4k_5 + 2k_1k_3k_4k_5 + k_1k_2k_4k_5 + 2k_1k_2k_3k_5}{k_2k_3k_4 + k_2k_3k_5 + 2k_1k_3k_4 + 2k_1k_3k_5 + k_1k_2k_4 + k_1k_2k_5 + 2k_1k_2k_3}$$

1.8



(a)



(b)

From Fig.(a), $x = x_1 + \dfrac{l_1}{l_1+l_2}(x_2 - x_1)$

$$= \frac{l_2}{l_1+l_2}\,x_1 + \frac{l_1}{l_1+l_2}\,x_2 \qquad (1)$$

Vertical force equilibrium from Fig.(b):

$$F = F_1 + F_2 \qquad (2)$$

Moment equilibrium about C′ (Fig.(b)):

$$F_2\, l_2 = F_1\, l_1 \qquad (3)$$

Solution of Eqs. (2) and (3):

$$F_1 = \frac{F\,l_2}{l_1+l_2}, \quad F_2 = \frac{F\,l_1}{l_1+l_2} \qquad (4)$$

Displacements of springs k_1 and k_2 are given by

$$x_1 = \frac{F_1}{k_1} = \frac{F\,l_2}{k_1(l_1+l_2)}, \quad x_2 = \frac{F_2}{k_2} = \frac{F\,l_1}{k_2(l_1+l_2)} \qquad (5)$$

Displacement of force F can be found using Eqs.(5) in Eq.(1):

$$x = \frac{l_2}{l_1+l_2}\cdot\frac{F\,l_2}{k_1(l_1+l_2)} + \frac{l_1}{l_1+l_2}\cdot\frac{F\,l_1}{k_2(l_1+l_2)}$$

$$= \frac{F}{(l_1+l_2)^2}\left(\frac{l_1^2 k_1 + l_2^2 k_2}{k_1 k_2}\right) \qquad (6)$$

The equivalent spring constant of the system in the direction of x, k_e, is given by Eq. (6):

$$k_e = \frac{F}{x} = \frac{(\ell_1 + \ell_2)^2 k_1 k_2}{\ell_1^2 k_1 + \ell_2^2 k_2} \qquad (7)$$

1.9 Equivalence of potential energies gives

$$\frac{1}{2} k_{t1} \theta^2 + \frac{1}{2} k_{t2} \theta^2 + \frac{1}{2} k_1 (\theta l_1)^2 + \frac{1}{2} k_2 (\theta l_1)^2 + \frac{1}{2} k_3 (\theta l_2)^2 = \frac{1}{2} k_{eq} \theta^2$$

$$\therefore \; k_{eq} = k_{t1} + k_{t2} + k_1 l_1^2 + k_2 l_1^2 + k_3 l_2^2$$

1.10 k_{123} = for series springs k_1, k_2 and k_3:

$$\frac{1}{k_{123}} = \frac{1}{k_1} + \frac{1}{k_2} + \frac{1}{k_3} \; ; \qquad k_{123} = \frac{k_1 k_2 k_3}{k_1 k_2 + k_2 k_3 + k_3 k_1}$$

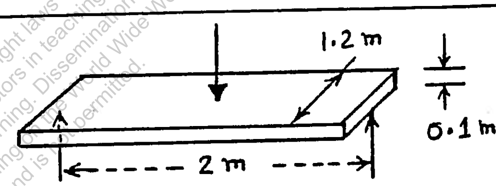
Using energy equivalence,

$$\frac{1}{2} k_{eq} \theta^2 = \frac{1}{2} k_4 \theta^2 + \frac{1}{2} k_{123} \theta^2 + \frac{1}{2} k_5 (\theta R)^2 + \frac{1}{2} k_6 (\theta R)^2$$

$$\therefore \; k_{eq} = k_4 + k_{123} + R^2 k_5 + R^2 k_6$$

$$= k_4 + \left(\frac{k_1 k_2 k_3}{k_1 k_2 + k_2 k_3 + k_3 k_1} \right) + R^2 (k_5 + k_6)$$

1.11 For simply supported beam, for load at middle,



$$k_1 = \frac{48 EI}{l^3} = \frac{48 (2.06 \times 10^{11})(10^{-4})}{8}$$

$= 12.36 \times 10^7$ N/m where $I = \frac{1}{12} (1.2)(0.1)^3 = 10^{-4}$ m^4.

$$\delta_1 = \text{original deflection} = \frac{mg}{k_1} = \frac{500 \times 9.81}{12.36 \times 10^7} = 396.8447 \times 10^{-7} \text{ m}$$

When spring k is added, $k_{eq} = k + k_1$.

(a) New deflection $= \dfrac{mg}{k_{eq}} = \dfrac{\delta_1}{4}$; $k_{eq} = \dfrac{4\,mg}{\delta_1} = 4 k_1 = k + k_1$

$\therefore \; k = 3 k_1 = 37.08 \times 10^7$ N/m

(b) New deflection $= \dfrac{mg}{k_{eq}} = \dfrac{\delta_1}{2}$; $k_{eq} = \dfrac{2\,mg}{\delta_1} = 2 k_1 = k + k_1$

$\therefore \; k = k_1 = 12.36 \times 10^7$ N/m

(c) New deflection $= \dfrac{mg}{k_{eq}} = \dfrac{3}{4} \delta_1$; $k_{eq} = \dfrac{4\,mg}{3\,\delta_1} = \dfrac{4}{3} k_1 = k + k_1$

$\therefore \; k = \frac{1}{3} k_1 = 4.12 \times 10^7$ N/m

(1.12) For a bar with length L, Young's modulus E and cross-section A, the axial stiffness (k) is given by

$$k = \frac{AE}{L} \qquad (1)$$

when cross-section is solid circular with diameter d,

$$\text{area} = A_1 = \pi d^2/4 \qquad (2)$$

when cross-section is square with side d,

$$\text{area} = A_2 = d^2 \qquad (3)$$

When cross-section is hollow circular with mean dia. d and wall thickness $t = 0.1d$,

$$\text{area} = \pi d t = \pi d (0.1 d) = 0.1 \pi d^2 \qquad (4)$$

For specified value of $k = \bar{k}$, cross-section area required is:

$$A = \frac{\bar{k} L}{E} = c \text{ (constant)} \qquad (5)$$

Weight of bar :

with solid circular section:

$$W_1 = \frac{\pi d^2}{4} L = c L \quad \text{with} \quad d^2 = \frac{4c}{\pi} \qquad (6)$$

with hollow circular section:

$$W_3 = 0.1 \pi d^2 L = 0.1 \pi \left(\frac{4c}{\pi}\right) L = 0.4 c L = 0.4 W_1 \qquad (7)$$

with square section:

$$W_2 = d^2 L = \frac{4c}{\pi} L = \frac{4}{\pi} W_1 = 1.2732 W_1 \qquad (8)$$

$\therefore$ The shaft with the hollow circular cross-section corresponds to minimum weight.

(1.13) Stiffness of a cantilever beam under a bending force at free end: $$k = \frac{3EI}{l^3} \quad (1)$$

For a specified value of $k = \bar{k}$,
$$I = \frac{\bar{k}\, l^3}{3E} = c = \text{constant} \quad (2)$$

For a solid circular section with diameter d,
$$I_1 = \frac{\pi d^4}{64} = c \Rightarrow d^4 = \frac{64\,c}{\pi} \quad \text{or} \quad d^2 = \sqrt{\frac{64\,c}{\pi}} \quad (3)$$

weight of beam $= W_1 = \frac{\pi d^2 l}{4} = \frac{\pi l}{4}\sqrt{\frac{64\,c}{\pi}}$
$$= 3.5449\, l \sqrt{c} \quad (4)$$

For a hollow circular section with mean diameter d and wall thickness $t = 0.1\, d$, weight of beam (W_2) is:
$$W_2 = \frac{\pi}{4}\left(d_o^4 - d_i^4\right) l = \frac{\pi l}{4}\left\{(d+t)^2 - (d-t)^2\right\}$$
$$= \frac{\pi l}{4}(4dt) = \pi d t l = \pi l \left(0.1\, d^2\right)$$
$$= 0.1\,\pi\, l \sqrt{\frac{64c}{\pi}} = 1.4180\, l \sqrt{c} \quad (5)$$

For a square section with side d, weight of the beam (W_3) is:
$$W_3 = d^2 l = l\sqrt{\frac{64\,c}{\pi}} = 4.5135\, l \sqrt{c} \quad (6)$$

By comparing Eqs. (4), (5) and (6), the minimum weight beam corresponds to the hollow circular cross-section.

(1.14) Spring force is given by $F = 800\,x + 40\,x^3$ (1)

static equilibrium of the rubber mounting (x^*) under the weight of the electronic instrument is given by

$$F = 200 = 800\,x^* + 40\,x^{*3}$$

or $$40\,x^{*3} + 800\,x^* - 200 = 0 \qquad (2)$$

The roots of the cubic equation (2) can be found from MATLAB as

$$x^* = 0.2492,\quad -0.1246 \pm 4.4773\,i \qquad (3)$$

Thus the static equilibrium position of the rubber mounting is given by the real root of Eq. (2):

$$x^* = 0.2492 \text{ in} \qquad (4)$$

(a) Equivalent linear spring constant of rubber mounting at its static equilibrium position, using Eq. (1.7), is:

$$k_{eq} = \left.\frac{dF}{dx}\right|_{x^*} = 800 + 120\,x^{*2} = 800 + 1200\,(0.2492)^2$$

$$= 807.4521 \text{ lb/in} \qquad (5)$$

(b) Deflection of rubber mounting corresponding to the equivalent linear spring constant is:

$$k = \frac{F}{k_{eq}} = \frac{200}{807.4521} = 0.2477 \text{ in} \qquad (6)$$

(1.15) $$F(x) = 200x + 50x^2 + 10x^3 \tag{1}$$

When the spring undergoes a steady deflection of $x^* = 0.5$ in during the operation of the engine, the force exerted on the spring can be found as

$$F = 200(0.5) + 50(0.5)^2 + 10(0.5)^3 = 113.75 \text{ lb} \tag{2}$$

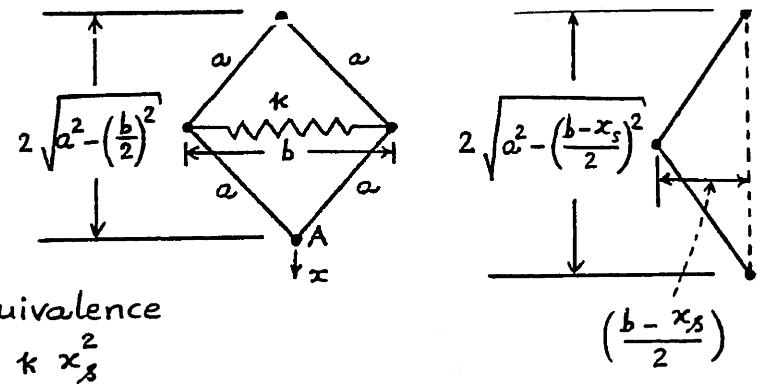
Equivalent linear spring constant at its steady deflection is given by Eq. (1.7):

$$k_{eq} = \left.\frac{dF}{dx}\right|_{x=x^*} = 200 + 100\, x^* + 30\, x^{*2}$$

$$= 200 + 100(0.5) + 30(0.5)^2$$

$$= 253.75 \text{ lb/in}$$

1.16 (a) x = downward deflection of point A, x_s = resulting deformation of spring



Potential energy equivalence gives $\frac{1}{2} k_{eq}\, x^2 = \frac{1}{2} k\, x_s^2$

$$k_{eq} = k\left(\frac{x_s}{x}\right)^2$$

But
$$x = 2\left[\sqrt{a^2-\left(\frac{b-x_s}{2}\right)^2} - \sqrt{a^2-\left(\frac{b}{2}\right)^2}\right]$$

$$= 2\sqrt{a^2-\left(\frac{b}{2}\right)^2}\left[\left\{\frac{a^2-\left\{\frac{b}{2}\left(1-\frac{x_s}{b}\right)\right\}^2}{a^2-\left(\frac{b}{2}\right)^2}\right\}^{1/2} - 1\right]$$

$$= 2\sqrt{a^2-\frac{b^2}{4}}\left[\left\{\frac{\left(a^2-\frac{b^2}{4}-\frac{x_s^2}{4}+\frac{b\,x_s}{2}\right)}{\left(a^2-\frac{b^2}{4}\right)}\right\}^{1/2} - 1\right]$$

$$= 2\sqrt{a^2-\frac{b^2}{4}}\left[\left\{1-\frac{\overbrace{x_s^2}^{\approx 0}}{\left(a^2-\frac{b^2}{4}\right)}+\frac{b\,x_s}{2\left(a^2-\frac{b^2}{4}\right)}\right\}^{1/2} - 1\right]$$

Using the relation $(1+\theta)^{1/2} \simeq 1+\frac{\theta}{2}$, we obtain

$$x = 2\left(a^2-\frac{b^2}{4}\right)^{1/2}\left[1+\frac{b\,x_s}{4\left(a^2-\frac{b^2}{4}\right)} - 1\right] = \frac{b\,x_s}{2\left(a^2-\frac{b^2}{4}\right)^{1/2}}$$

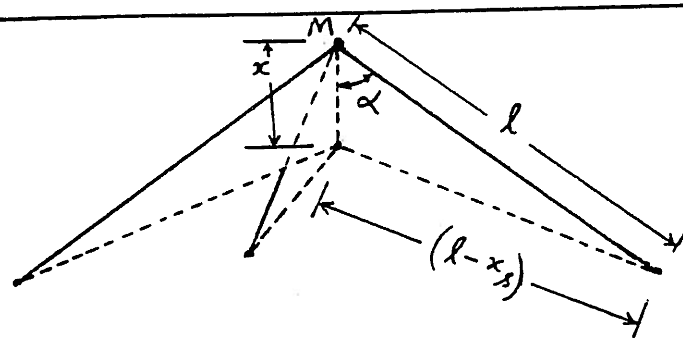
$$\therefore\ k_{eq} = k\left(\frac{x_s}{x}\right)^2 = 4k\left(\frac{a^2-\frac{b^2}{4}}{b^2}\right) = k\left(\frac{4a^2-b^2}{b^2}\right)$$

(b) Here $x = x_s$ (spring deflection)

$$\therefore\ k_{eq} = k$$

1.17 Let x = vertical displacement of mass M,

x_s = resulting deformation of each inclined spring.



From equivalence of potential energy,

$$\frac{1}{2} k_{eq}\, x^2 = 3\left(\frac{1}{2} k\, x_s^2\right) \; ; \qquad k_{eq} = 3k\left(\frac{x_s}{x}\right)^2$$

From geometry,

$$(l - x_s)^2 = l^2 + x^2 - 2\,l\,x \cos\alpha$$

$$x^2 - 2x\,l\cos\alpha + 2\,l\,x_s - x_s^2 = 0 \qquad (E_1)$$

Solving (E_1),

$$x = l\cos\alpha\left[1 \pm \left\{1 - \frac{(2\,l\,x_s - x_s^2)}{l^2\cos^2\alpha}\right\}^{1/2}\right] \qquad (E_2)$$

Using the relation $\sqrt{1-\theta} \approx 1 - \frac{\theta}{2}$, (E_2) can be rewritten as

$$x = l\cos\alpha\left[1 \pm \left\{1 - \left(\frac{2\,l\,x_s - x_s^2}{2\,l^2\cos^2\alpha}\right)\right\}\right] \qquad (E_3)$$

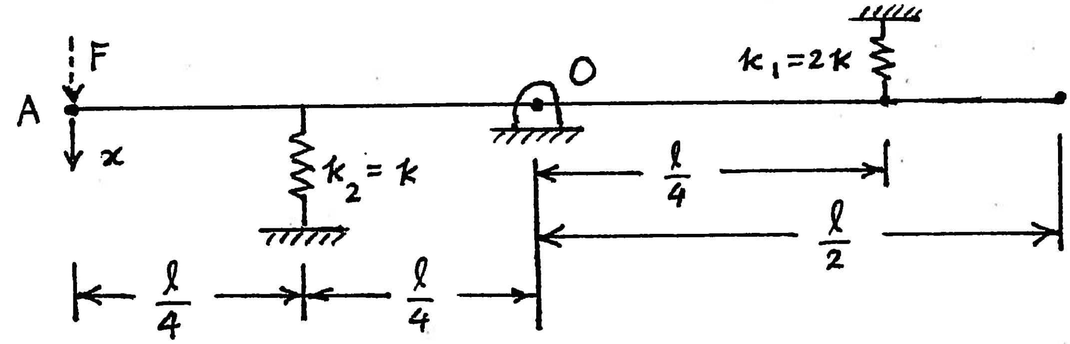
Assuming x to be small, we use minus sign and neglect x_s^2 compared to $2\,l\,x_s$ in (E_3). This gives

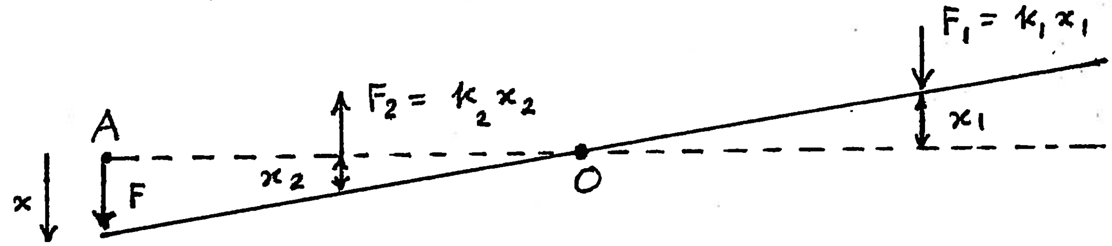
$$x = \frac{x_s}{\cos\alpha}$$

$$\therefore \quad k_{eq} = 3\,k\cos^2\alpha$$

In a similar manner, $c_{eq} = 3\,c\cos^2\alpha$

1.18





$$x_2 = \frac{x}{2}, \quad x_1 = \frac{x}{2}$$

$$F_2 = k_2 x_2 = \frac{k x}{2}, \quad F_1 = k_1 x_1 = 2k\left(\frac{x}{2}\right) = kx$$

Equivalent spring constant of the system (k_{eq}) at point A can be determined by considering the moment equilibrium of forces about the pivot point O:

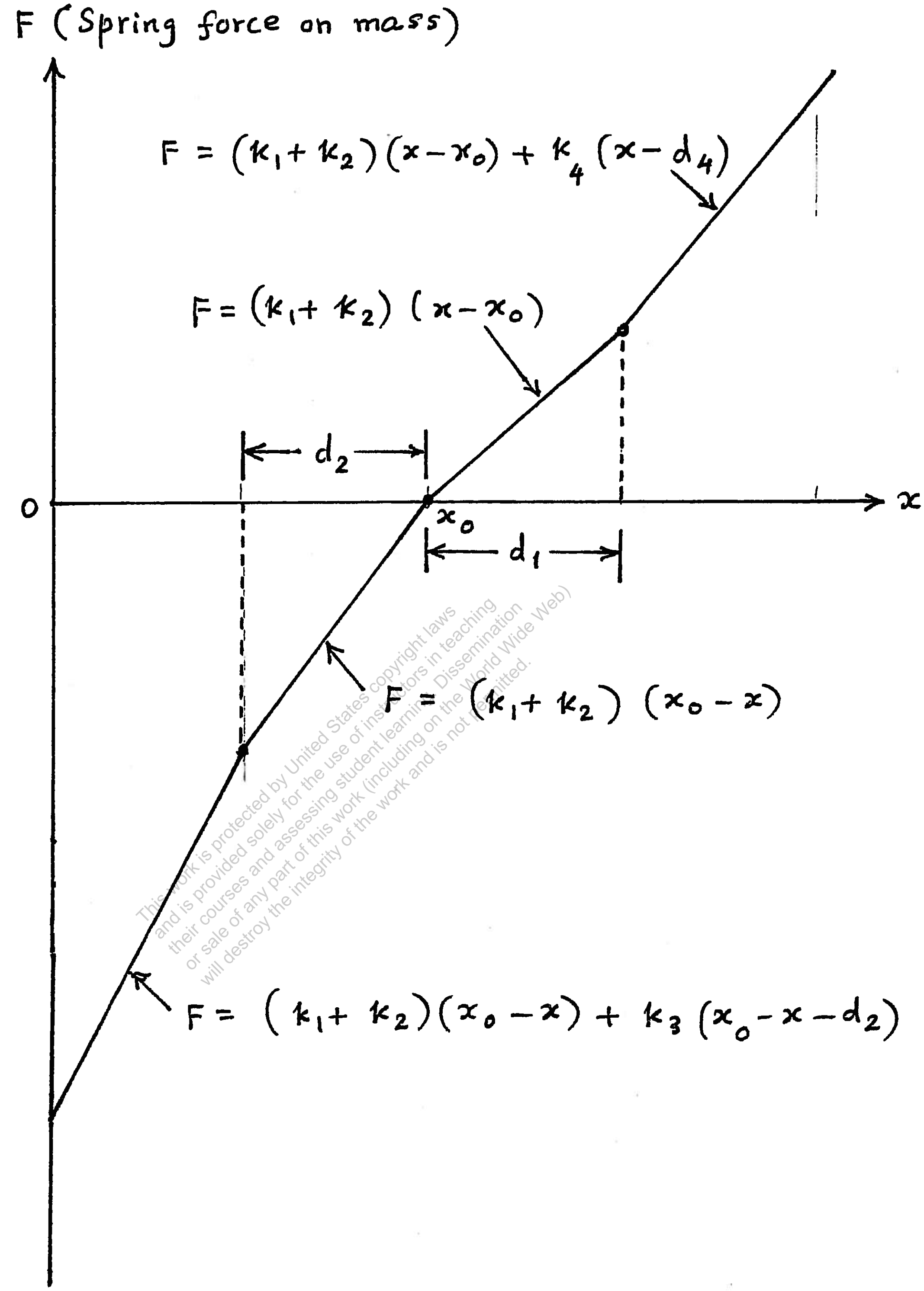
$$F\left(\frac{l}{2}\right) - F_2\left(\frac{l}{4}\right) - F_1\left(\frac{l}{4}\right) = 0$$

$$F = \frac{F_2}{2} + \frac{F_1}{2} = \frac{kx}{4} + \frac{kx}{2} = \frac{3}{4} kx$$

$$= k_{eq}\, x$$

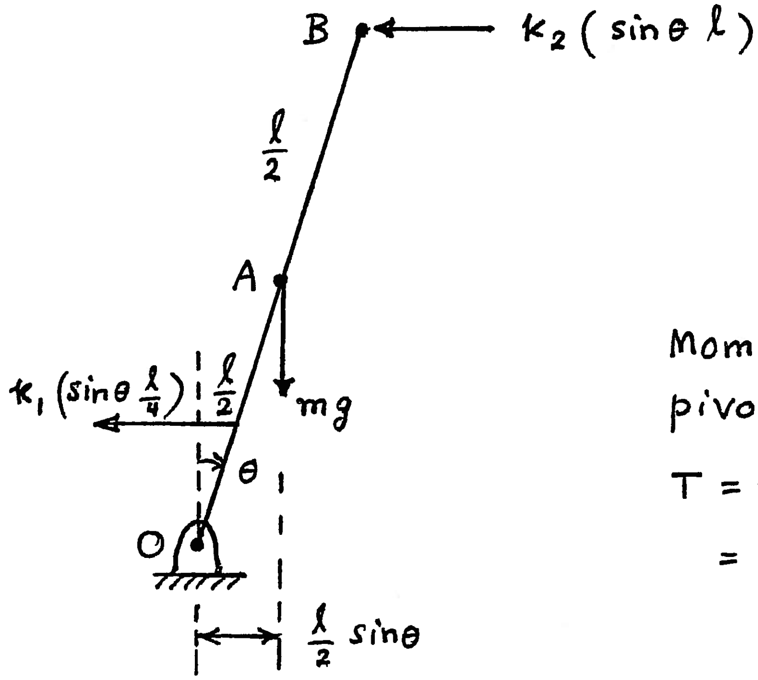
$$\therefore \quad k_{eq} = \frac{3}{4} k$$

1.19



F (Spring force on mass)
$F = (k_1 + k_2)(x - x_0) + k_4 (x - d_4)$
$F = (k_1 + k_2)(x - x_0)$
d_2
0
x
x_0
d_1
$F = (k_1 + k_2)(x_0 - x)$
$F = (k_1 + k_2)(x_0 - x) + k_3 (x_0 - x - d_2)$

(1.20)



Moment about the pivot point O:

$$
\begin{aligned}
T &= \text{moment} \\
&= mg\,\frac{l}{2}\sin\theta - \left(k_1 \frac{l}{4}\sin\theta\right)\frac{l}{4} \\
&\quad - \left(k_2\, l \sin\theta\right) l \\
&\simeq \left(\frac{mgl}{2} - k_1 \frac{l^2}{16} - k_2 l^2\right)\theta
\end{aligned}
\tag{1}
$$

Denoting the equivalent torsional spring constant of the system as k_t, the moment T can be expressed as

$$T = k_t\ \theta \tag{2}$$

By equating Eqs. (1) and (2), we obtain

$$k_t = \frac{mgl}{2} - \frac{k_1 l^2}{16} - k_2 l^2 \tag{3}$$

1.21 When mercury is displaced by an amount x in one leg of the manometer (Fig. 1.77), the mercury column will undergo a total displacement of $2x$. The magnitude of the force, due to the weight of the displaced mercury, acts on the rest of the fluid. The restoring force is given by

$$F = 2\gamma A x \tag{1}$$

where γ is the specific weight of mercury and A is the cross-sectional area of the manometer tube. If k_{eq} denotes the spring constant associated with the restoring force, the restoring force can be expressed as

$$F = k_{eq}\, x \tag{2}$$

Equations (1) and (2) yield the equivalent spring constant as

$$k_{eq} = 2\gamma A \tag{3}$$

(1.22) When the drum is displaced by an amount x from its static equilibrium position, the weight of the fluid (sea water) displaced is given by

$$W = \rho_w g \left(\frac{\pi d^2}{4}\right) x \qquad (1)$$

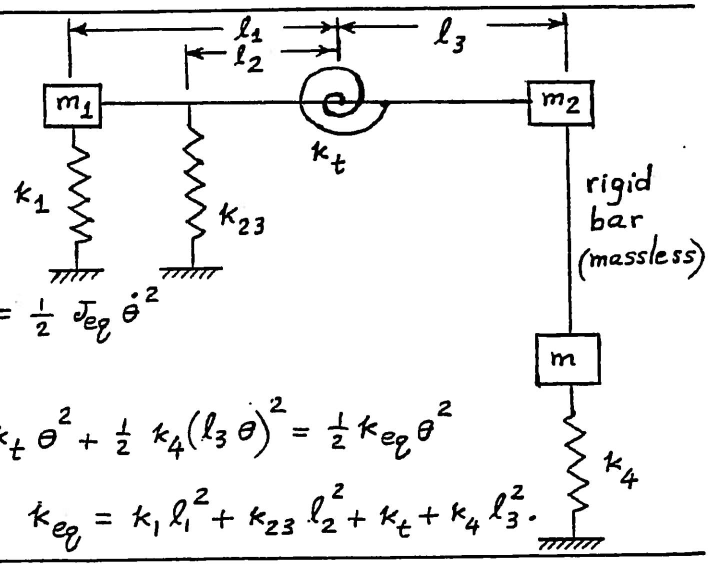
where ρ_w is the density of sea water and g is the acceleration due to gravity. The weight, W, given by Eq. (1) also denotes the restoring force F. By expressing the restoring force as

$$F = k_{eq}\, x \qquad (2)$$

where k_{eq} denotes the equivalent spring constant associated with the restoring force. Equating (1) and (2), we obtain

$$k_{eq} = \rho_w g \frac{\pi d^2}{4} \qquad (3)$$

1.23



$$k_{23} = \frac{k_2 k_3}{k_2 + k_3}$$

$$k_4 = A \rho g = \frac{\pi d^2}{4} \rho g$$

From kinetic energy,

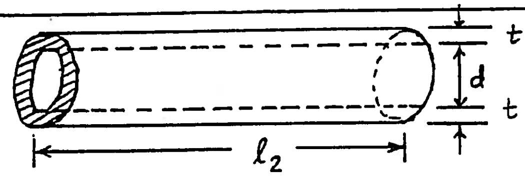
$$\frac{1}{2} m_1 (l_1 \dot{\theta})^2 + \frac{1}{2}(m_2 + m)(l_3 \dot{\theta})^2 = \frac{1}{2} J_{eq} \dot{\theta}^2$$

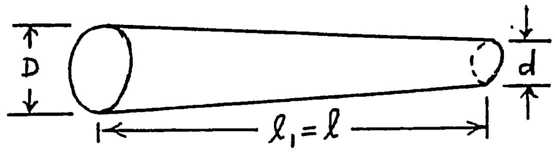
From potential energy,

$$\frac{1}{2} k_1 (l_1 \theta)^2 + \frac{1}{2} k_{23} (l_2 \theta)^2 + \frac{1}{2} k_t \theta^2 + \frac{1}{2} k_4 (l_3 \theta)^2 = \frac{1}{2} k_{eq} \theta^2$$

$$\therefore \; J_{eq} = m_1 l_1^2 + (m_2 + m) l_3^2 \; ; \qquad k_{eq} = k_1 l_1^2 + k_{23} l_2^2 + k_t + k_4 l_3^2 .$$

1.24





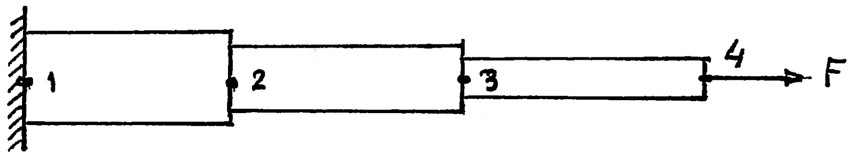
$$k_2 = \frac{EA}{l_2} = \frac{\pi E t (d + t)}{l_2} \qquad k_1 = \frac{\pi E D d}{4 l}$$

$$k_2 = k_1 \text{ gives } \quad l_2 = \frac{4 t (d + t)}{D d}$$

1.25 (a) Spring constant (stiffness) of step i in the axial direction:

$$k_i = \frac{A_i E_i}{l_i} = \frac{A_i E}{l_i}, \quad i = 1,2,3 \qquad (1)$$

(b)



The reaction at any point along the stepped shaft due to an axial force (F) applied at point 4 will be same as F. Hence the springs (stiffnesses) corresponding to the three steps 12, 23 and 34 are to be considered as series springs. In view of Eq.(1), the equivalent spring constant given by Eq. (1.17) becomes

$$\frac{1}{k_{eq}} = \frac{1}{k_1} + \frac{1}{k_2} + \frac{1}{k_3} = \frac{1}{E}\left(\frac{l_1}{A_1} + \frac{l_2}{A_2} + \frac{l_3}{A_3}\right)$$

$$= \frac{1}{E} \, \frac{(l_1 A_2 A_3 + l_2 A_1 A_3 + l_3 A_1 A_2)}{A_1 A_2 A_3}$$

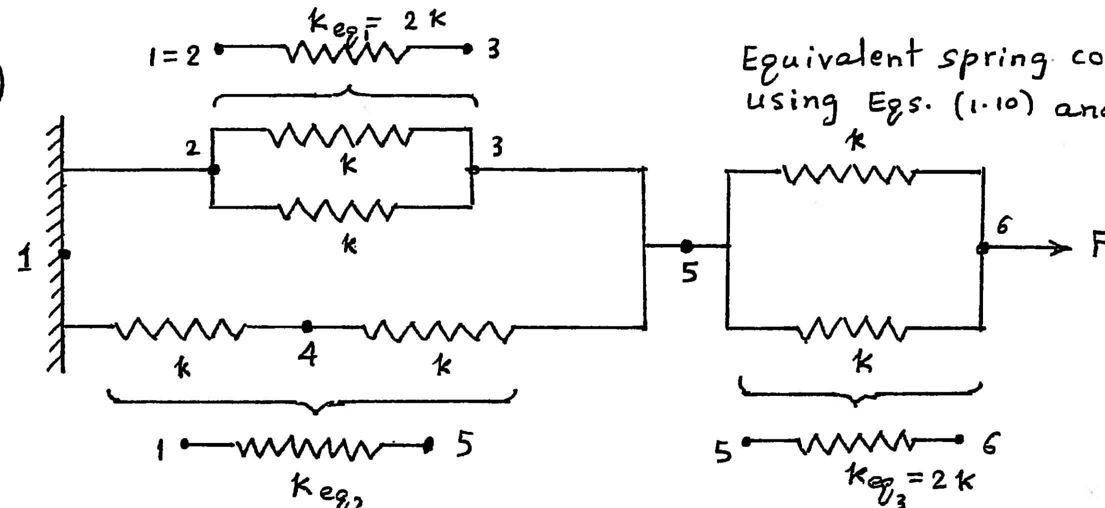
or

$$k_{eq} = \frac{E A_1 A_2 A_3}{l_1 A_2 A_3 + l_2 A_1 A_3 + l_3 A_1 A_2} \qquad (2)$$

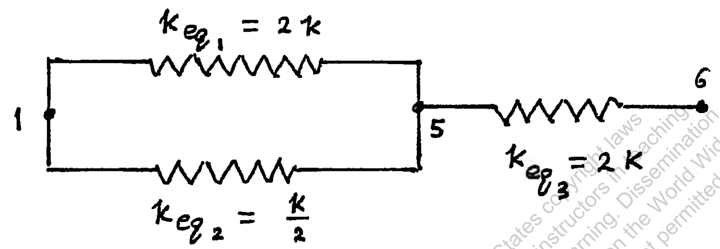
(c) steps behave as series springs.

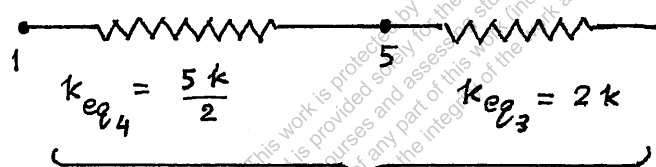
1.26

Equivalent spring constants using Eqs. (1.10) and (1.16).



$$\frac{1}{k_{eq_2}} = \frac{1}{k} + \frac{1}{k} \Rightarrow k_{eq_2} = \frac{k}{2}$$





$$k_{eq_5} \Rightarrow \frac{1}{k_{eq_5}} = \frac{1}{k_{eq_4}} + \frac{1}{k_{eq_3}} = \frac{2}{5k} + \frac{1}{2k}$$

$$k_{eq_5} = \frac{10}{9} k$$

$$k_{eq} = k_{eq_5} = \frac{10}{9} k$$

1.27 (a) Torsional spring constant or stiffness of step i is

$$k_{t_i} = \frac{G_i J_i}{l_i} = \frac{G_i \pi D_i^4}{32 l_i}, \quad i = 1, 2, 3 \qquad (1)$$

(b) The reactive torque at any point along the stepped shaft due to an applied torque T at the free end will be T. Hence the torsional stiffnesses (springs) corresponding to the three steps 12, 23 and 34 are to be considered as series springs. In view of Eq. (1), the equivalent torsional spring constant given by Eq. (1.17) becomes (Eq. (1.17) is to be interpreted for torsional springs):

$$\frac{1}{k_{eq}} = \frac{1}{k_{t1}} + \frac{1}{k_{t2}} + \frac{1}{k_{t3}} = \frac{32}{\pi G}\left(\frac{l_1}{D_1^4} + \frac{l_2}{D_2^4} + \frac{l_3}{D_3^4}\right)$$

$$= \frac{32}{\pi G}\left(\frac{l_1 D_2^4 D_3^4 + l_2 D_1^4 D_3^4 + l_3 D_1^4 D_2^4}{D_1^4 D_2^4 D_3^4}\right)$$

or

$$k_{eq} = \frac{\pi G D_1^4 D_2^4 D_3^4}{32\left(l_1 D_2^4 D_3^4 + l_2 D_1^4 D_3^4 + l_3 D_1^4 D_2^4\right)} \qquad (2)$$

(c) steps behave as series springs.

1.28 (a) $F \simeq F\big|_{x_0} + \frac{dF}{dx}\big|_{x_0} \cdot (x - x_0) = \left(500x + 2x^3\right)_{x=10} + \left(500 + 6x^2\right)_{x=10} \cdot (x-10)$

$\simeq 1100\,x - 4000$

(b) at $x = 9$ mm :

Exact $F_9 = 500 \times 9 + 2\,(9)^3 = 5958$ N

Approximate $F_9 = 1100 \times 9 - 4000 = 5900$ N

Error $= -0.9735\,\%$

(c) at $x = 11$ mm :

Exact $F_{11} = 500 \times 11 + 2\,(11)^3 = 8162$ N

Approximate $F_{11} = 1100 \times 11 - 4000 = 8100$ N

Error $= +0.7596\,\%$

1.29 $p v^{\gamma} = \text{constant}$ --- (E_1) ; Differentiation of (E_1) gives

$$dp\; v^{\gamma} + p\, \gamma\, v^{\gamma - 1}\, dv = 0$$

$$dp = -\frac{p\gamma}{v}\, dv \quad \text{---}(E_2)$$

change in volume when mass moves by dx, $dv = -A \cdot dx$ --- (E_3)

Eqs. (E_2) and (E_3) give $dp = \frac{p \gamma A}{v}\, dx$

Force due to pressure change $= dF = dp \cdot A = \frac{p\gamma A^2}{v} \cdot dx$

spring constant of air spring $= k = \frac{dF}{dx} = \left(\frac{p\gamma A^2}{v}\right)$.

1.30 Equivalent spring constants in diffent directions are

$$k_{e1} = \left(\frac{k_5\, k_6\, k_7}{k_5 k_6 + k_5 k_7 + k_6 k_7}\right), \quad k_{e2} = \left(\frac{k_8\, k_9}{k_8 + k_9}\right),$$

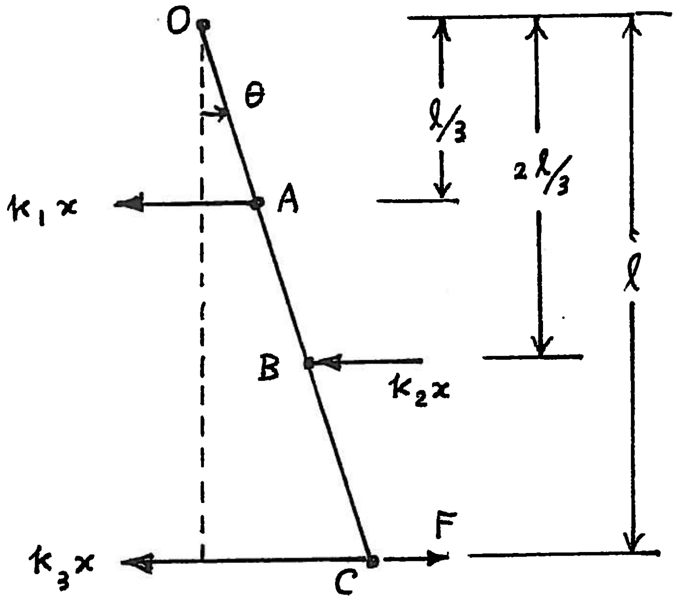
$$k_{e3} = \left(\frac{k_1\, k_2}{k_1 + k_2}\right), \quad k_{e4} = \left(\frac{k_3\, k_4}{k_3 + k_4}\right)$$

If the force P moves by x, spring located at θ_i undergoes a displacement of $x_i = x \cos\theta_i$ (derivation as in problem 1.17).

Equivalence of potential energy gives $\frac{1}{2} k_{eq}\, x^2 = \frac{1}{2} \sum_{i=1}^{4} k_{ei}\, x_i^2$

$$k_{eq} = \sum_{i=1}^{4} \left(k_{ei} \cos^2\theta_i\right)$$

(1.31)



Let the link OABC undergo a small angular displacement θ as shown in above figure. The spring reaction forces are also indicated in the figure. Equilibrium of moments about the pivot point O gives:

$$-k_1 x\left(\frac{l}{3}\right) - k_3 x\,(l) - k_2 x\left(\frac{2l}{3}\right) + F\,(l) = 0$$

or
$$F = \left(\frac{k_1}{3} + \frac{2}{3}k_2 + k_3\right)x \qquad (1)$$

If k_{eq} denotes the equivalent spring constant of the link along the direction of F at point C, we have

$$F = k_{eq}\, x \qquad (2)$$

Equations (1) and (2) give

$$k_{eq} = \frac{k_1}{3} + \frac{2\,k_2}{3} + k_3 = \frac{k}{3} + \frac{2}{3}(2k) + (3k)$$

$$\therefore\ k_{eq} = \frac{14}{3}\,k \qquad (3)$$

(1.32) Spring constant of a helical spring is

$$k = \frac{G d^4}{8 N D^3} \qquad (1)$$

Assuming the shear modulus of steel as $G = 79.3$ GPa, Eq. (1) gives, for $D = 0.2$ m, $d = 0.005$ m and $N = 10$,

$$k = \frac{(79.3 \times 10^9)(0.005)^4}{8\,(10)\,(0.2)^3} = 77.4414 \text{ N/m}$$

(1.33) (a) D and d: same for both helical springs

Weight of a helical spring is:

$$W = \pi D \left(\frac{\pi d^2}{4}\right) N \gamma \qquad (1)$$

where γ = specific weight of material of spring.

For a steel spring with $\gamma_s = 76.5 \ kN/m^3$, the weight is (for $N_s = 10$):

$$W_s = \pi D \left(\frac{\pi d^2}{4}\right) N_s \gamma_s = \frac{\pi^2 D d^2}{4} (10)(76.5 \times 10^3)$$

$$= 19.125 \times 10^4 \ \pi^2 D d^2 \qquad (2)$$

For an aluminum spring with $\gamma_a = 26.6 \ kN/m^3$, the weight is (for number of turns N_a),

$$W_a = \pi D \left(\frac{\pi d^2}{4}\right) N_a \gamma_a = \frac{\pi^2 D d^2 N_a}{4} (26.6 \times 10^3)$$

$$= 6.65 \times 10^3 \ \pi^2 D d^2 N_a \qquad (3)$$

Equating (2) and (3),

$$19.125 \times 10^4 \ \pi^2 D d^2 = 6.65 \times 10^3 \ \pi^2 D d^2 N_a$$

or $$N_a = \frac{19.125 \times 10^4}{6.65 \times 10^3} = 28.7594 \qquad (4)$$

(b) Spring constant of a helical spring is:

$$k = G d^4 / (8 N D^3)$$

For a steel spring with G = 79.3 GPa,

$$k_s = (79.3 \times 10^9) d^4 / \{8 (10) D^3\}$$

$$= 0.99125 \times 10^9 \ d^4 / D^3 \qquad (5)$$

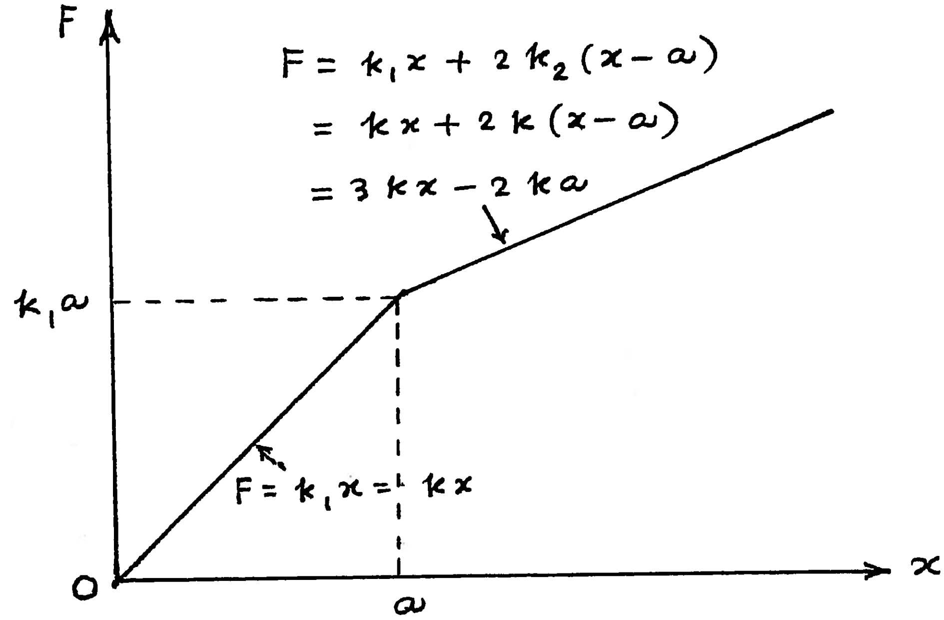
For an aluminum spring with G = 26.2 GPa,

$$k_a = (26.2 \times 10^9) d^4 / \{8 (28.7594) D^3\}$$

$$= 0.1139 \times 10^9 \ d^4 / D^3 \qquad (6)$$

Eqs. (5) and (6) indicate that the spring constant of steel spring is $0.99125/0.1139 = 8.7046$ times larger than that of aluminum spring.

1.34



(1.35) From Problem 1.29, $k = \dfrac{p \gamma A^2}{v}$ with $\gamma = 1.4$ for air

Let $p = 200$ psi

$k = 75$ lb/in $= \dfrac{(200)(1.4)\,A^2}{v} \Rightarrow \dfrac{A^2}{v} = 0.2679$

Let diameter of piston $= d = 2$ inch ; $A = \dfrac{\pi}{4}(2)^2 = 3.1416$ in^2

$v = A^2/0.2679 = 36.8408$ in^3

Let $h = 2$ inch ; $\dfrac{\pi}{4} D^2 (2) = v \Rightarrow D = 4.8429$ inch

---

(1.36) $F = a\,x + b\,x^3 = 2\,(10^4)\,x + 4\,(10^7)\,x^3$

Around x^*: $F(x) \approx F(x^*) + \dfrac{dF}{dx}\Big|_{x^*} (x - x^*)$

When $x^* = 10^{-2}$ m, $F(x^*) = 2\,(10^4)\,(10^{-2}) + 4\,(10^7)\,(10^{-6}) = 240$ N

$\dfrac{dF}{dx}\Big|_{x^*} = a + 3\,b\,x^2 = 2\,(10^4) + 3\,(4)\,(10^7)\,(10^{-4}) = 32000$

Hence $F(x) = 240 + 32000\,(x - 0.01) = (32000\,x - 80)$ N

Since the linearized spring constant is given by $F(x) = k_{eq}\,x$, we have $k_{eq} = 32{,}000$ N/m.

(1.37) $F_i = a_i\, x_i + b_i\, x_i^3 \; ; \; i = 1, 2$

Springs in series:

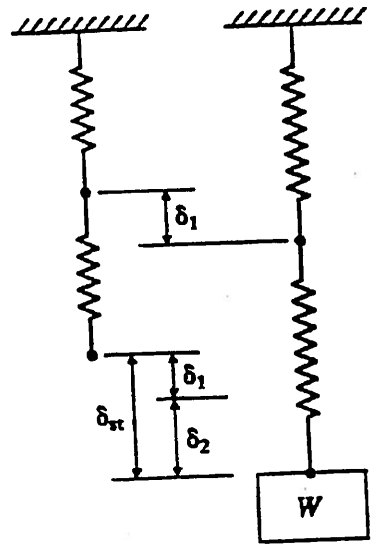
$$W = a_1 \delta_1 + b_1 \delta_1^3 \quad (1)$$

$$W = a_2 \delta_2 + b_2 \delta_2^3 \quad (2)$$

$$W = k_{eq}\, \delta_{st} \quad (3)$$

$$\delta_{st} = \delta_1 + \delta_2 \quad (4)$$

Solve Eqs. (1) and (2) for δ_1 and δ_2, respectively. Substitute the result in Eq. (4) and then in Eq. (3) to find k_{eq}.



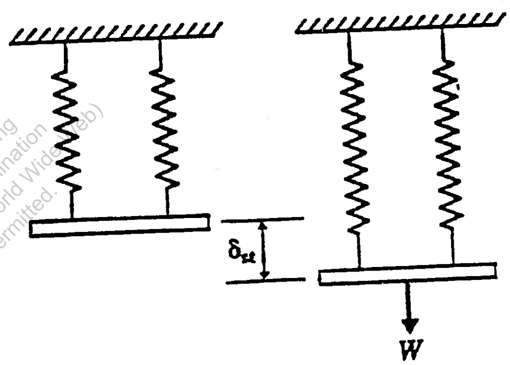
Springs in parallel:

$$W = F_1 + F_2$$

$$= a_1 \delta_{st} + b_1 \delta_{st}^3 + a_2 \delta_{st} + b_2 \delta_{st}^3$$

$$= k_{eq}\, \delta_{st}$$

$$k_{eq} = a_1 + b_1 \delta_{st}^2 + a_2 + b_2 \delta_{st}^2$$



1.38 $k = \dfrac{G\,d^4}{8\,D^3\,N} \geq 8 \times 10^6$ N/m ; $\dfrac{D}{d} \geq 6$; $N \geq 10$

$W = \pi D N \rho \left(\dfrac{\pi d^2}{4}\right)$ where ρ = weight per unit volume

$$f_1 = \frac{1}{2}\sqrt{\frac{k g}{W}} = \frac{1}{2}\sqrt{\frac{G\,d^2\,g}{2\,\pi^2\,D^4\,N^2\,\rho}} \geq 0.4 \text{ Hz}$$

Using $G = 73.1 \times 10^9$ N/m^2 , $\rho = 76000$ N/m^3 , $g = 9.81$ m/sec^2,
$\dfrac{D}{d} = 6, 8, 10$; $N = 10, 15, 20$; $d = 0.4, 0.6, \ldots,$ values of k and f_1 are computed.

Combination of $\dfrac{D}{d} = 6$, $N = 10$ and $d = 2.0$ m, corresponding to $k = 8.4606 \times 10^6$ N/m and $f_1 = 0.4801$ Hz, can be taken as an acceptable design.

1.39 Total elongation (strain) is same in each material:

$$\epsilon_s = \epsilon_a = \frac{x}{\ell} \tag{1}$$

where x is the total elongation. Equation (1) can be expressed as

$$\frac{\sigma_s}{E_s} = \frac{\sigma_a}{E_a} = \frac{x}{\ell} \tag{2}$$

$$\text{or} \quad \sigma_s = \frac{E_s\,x}{\ell} \tag{3}$$

$$\sigma_a = \frac{E_a\,x}{\ell} \tag{4}$$

Total axial force is:

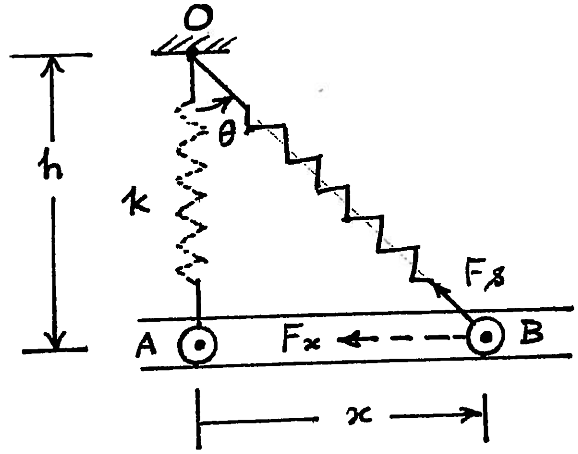
$$F = F_s + F_a = \sigma_s\,A_s + \sigma_a\,A_a \tag{5}$$

where F_s and F_a denote the axial forces acting on steel and aluminum, respectively, and A_s and A_a represent the cross-sectional areas of the two materials. Equating F to k_{eq} x where k_{eq} denotes the equivalent spring constant of the bimetallic bar, we obtain from Eqs. (3) to (5):

$$F = k_{eq}\,x = \left(\frac{E_s\,x}{\ell}\right) A_s + \left(\frac{E_a\,x}{\ell}\right) A_a$$

$$\text{or} \quad k_{eq} = \frac{E_s\,A_s}{\ell} + \frac{E_a\,A_a}{\ell} \tag{6}$$

1.40 Let the length of the spring be h. Spring is undeformed at $\theta = 0$. When the end A of the spring is displaced by an amount x as shown in the figure,



the spring is stretched by the amount $\left(\sqrt{h^2+x^2} - h\right)$ so that the force in the spring (F_s) is given by

$$F_s = k\left(\sqrt{h^2+x^2} - h\right) \tag{1}$$

The component of the spring force F_s along the direction of x is given by

$$F_x = F_s \sin\theta = F_s \frac{x}{\sqrt{h^2+x^2}} = \frac{k\left(\sqrt{h^2+x^2} - h\right)x}{\sqrt{h^2+x^2}}$$

$$= k\left(1 - \frac{h}{\sqrt{h^2+x^2}}\right)x \tag{2}$$

Equation (2) shows that the force-displacement relation (in the x-direction) is nonlinear. If the relation is linear, we could write

$$F_x = \underset{\sim}{k}\, x \tag{3}$$

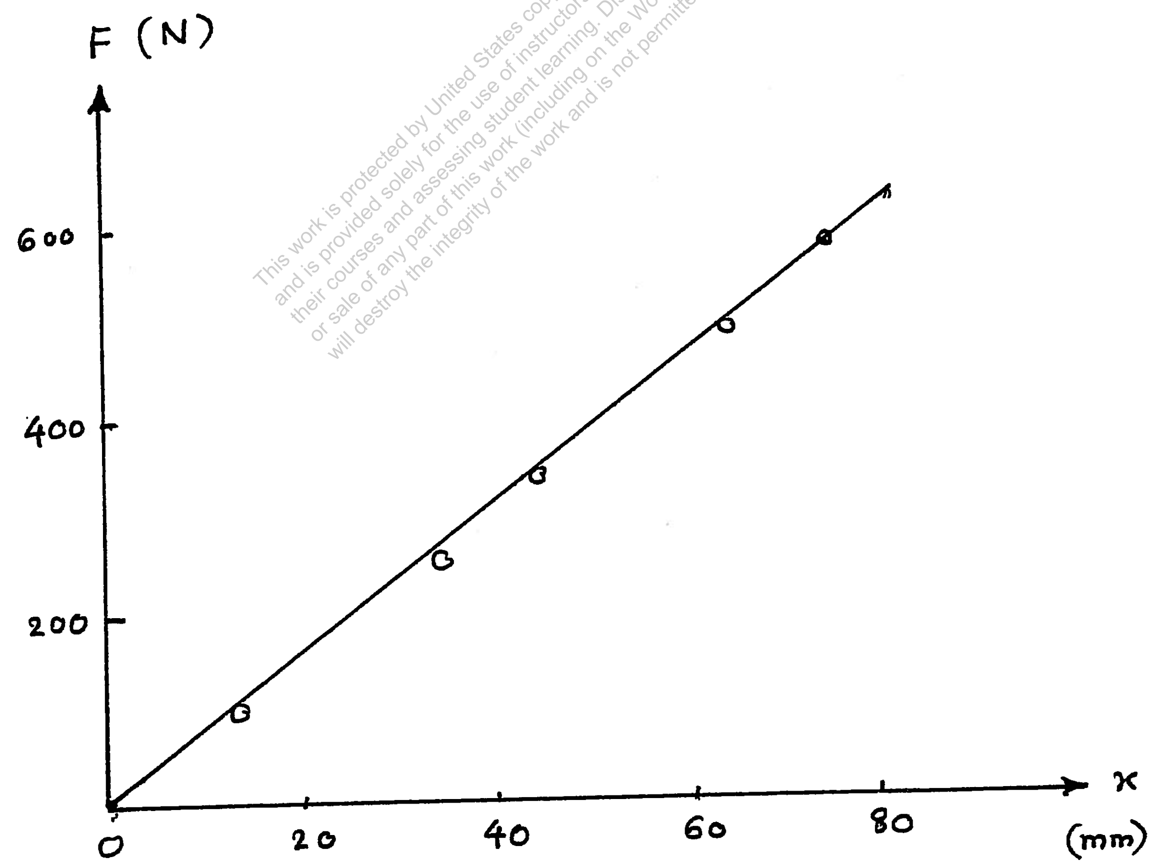
A comparison of Eqs. (2) and (3) shows that the spring constant $\underset{\sim}{x}$ is not a constant, but depends on the displacement x.

1.41 From the given data, the force - deformation relation of the spring can be obtained as :

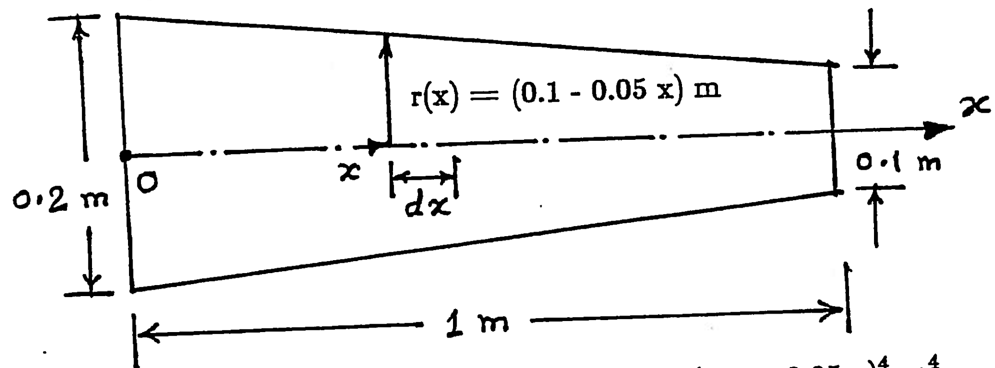
Tensile force (F), N	0	100	250	330	480	570
Deformation of spring (x), mm (change in length)	0	13	33	44	64	76

The force - deformation relation is plotten in the figure shown below. The relation can be seen to be nearly linear with the spring constant given by

$$k = \frac{F}{x} \simeq \frac{570}{76} = 7.5 \text{ N/mm} = 7500 \text{ N/m}.$$



1.42



$J = \dfrac{\pi}{2}\, r^4$ = area polar moment of inertia at section $x = 1.5708\,(0.1 - 0.05\,x)^4\ \mathrm{m}^4$

Knowing that the angle of twist, θ, between the ends of a uniform shaft of length ℓ under a torque T is given by $\theta = \dfrac{T\,\ell}{GJ}$, the angle of twist for an element of length dx can be expressed as

$$d\theta = \frac{T\,dx}{GJ} = \frac{T\,dx}{(80\,(10^9))\,1.5708\,(0.1 - 0.05\,x)^4} \tag{1}$$

The total angle of twist can be determined by integrating Eq. (1) from x=0 to 1 as:

$$\theta = \int_0^1 \frac{T\,dx}{(12.5664\,(10^{10}))\,(0.1 - 0.05\,x)^4} = \left(\frac{T}{12.5664\,(10^{10})}\right) \int_0^1 \frac{dx}{(0.1 - 0.05\,x)^4} \tag{2}$$

But $\displaystyle\int_0^1 \frac{dx}{(0.1 - 0.05\,x)^4} = -\frac{1}{0.05}\int_0^1 \frac{(-0.05\,dx)}{(0.1 - 0.05\,x)^4} = -20\int_0^{-0.05} \frac{dy}{(0.1 + y)^4}$

$= 4.6667\,(10^4)$ where $y = -0.05\,x$

Hence $\theta = \dfrac{T\,(4.6667)\,(10^4)}{12.5664\,(10^{10})} = T\,(0.3714\,(10^{-6}))$ rad

This gives $k_t = \dfrac{T}{\theta} = 2.6925\,(10^6)$ N-m/rad

---

1.43 The steel and aluminum hollow shafts can be treated as two torsional springs in parallel.

For a hollow shaft,

$k_t = \dfrac{\pi\,G}{32\,\ell}\,(D^4 - d^4)$

For the steel shaft, $G = 80\,(10^9)$ Pa, $\ell = 5$ m, $D = 0.25$ m, $d = 0.15$ m, and hence

$k_{t_1} = \dfrac{\pi\,(8\,(10^{10}))}{32\,(5)}\,(0.25^4 - 0.15^4) = 5.34072\,(10^6)$ N–m/rad

(a) For the aluminum shaft, $G = 26\,(10^9)$ Pa, $\ell = 5$ m, $D = 0.15$ m, $d = 0.1$ m, and hence

$k_{t_2} = \dfrac{\pi\,(26\,(10^9))}{32\,(5)}\,(0.15^4 - 0.10^4) = 0.207395\,(10^6)$ N–m/rad

$k_{eq} = k_{t_1} + k_{t_2} = 5.34072\,(10^6) + 0.20739\,(10^6) = 5.54811\,(10^6)$ N–m/rad

(b) With $G = 26\,(10^9)$ Pa, $\ell = 5$ m, $D = 0.15$ m and $d = 0.05$ m,

$$k_{t_2} = \frac{\pi\,(26\times 10^9)}{32\,(5)}\left(0.15^4 - 0.05^4\right) = 0.255255 \times 10^6 \text{ N-m/rad}$$

$$k_{eq} = k_{t_1} + k_{t_2} = 5.34072 \times 10^6 + 0.255255 \times 10^6 = 5.595975 \times 10^6 \text{ N-m/rad}$$

(1.44) For helical spring: $k = \dfrac{G\,d^4}{64\,n\,R^3}$

Spring 1: $k_1 = \dfrac{(12 \times 10^6)(2^4)}{64\,(10)(6^3)} = 1{,}388.89$ lb/in

Spring 2: $k_2 = \dfrac{(4 \times 10^6)(1^4)}{64\,(10)(5^3)} = 50.00$ lb/in

(a) Spring 2 inside spring 1 (parallel): $k_{eq} = k_1 + k_2 = 1{,}438.89$ lb/in
(b) Spring 2 on top of spring 1 (series):

$$\frac{1}{k_{eq}} = \frac{1}{k_1} + \frac{1}{k_2} = \frac{k_2 + k_1}{k_1\,k_2}$$

which gives $k_{eq} = 48.2625$ lb/in.

(1.45) For a helical spring, $k = \dfrac{G\,d^4}{64\,n\,R^3}$

$$k_1 = \frac{(12\times 10^6)(1)^4}{64\,(10)\,(6^3)} = 86.806 \text{ lb/in}$$

$$k_2 = \frac{(4\times 10^6)(0.5)^4}{64\,(10)\,(5^3)} = 3.125 \text{ lb/in}$$

(a) Spring 2 inside spring 1: $k_{eq} = k_1 + k_2 = 89.931$ lb/in

(b) Spring 2 on top of spring 1: $\dfrac{1}{k_{eq}} = \dfrac{1}{k_1} + \dfrac{1}{k_2}$

or $k_{eq} = \dfrac{k_1\,k_2}{k_1 + k_2} = \dfrac{86.806\,(3.125)}{86.806 + 3.125} = 3.0164$ lb/in

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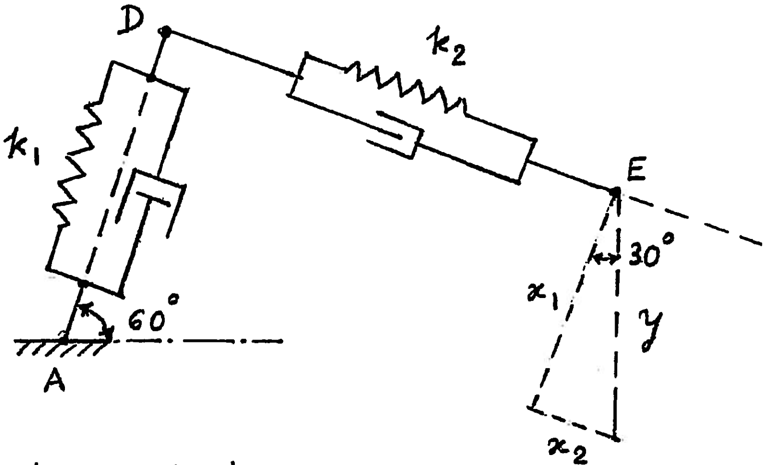
1.46



$x_2 = y \sin 30°$

$x_1 = y \cos 30°$

Equivalence of strain energies:

$$\frac{1}{2} k_{eq}\, y^2 = \frac{1}{2} k_2 x_2^2 + \frac{1}{2} k_1 x_1^2 = \frac{1}{2} k_1 y^2 \cos^2 30° + \frac{1}{2} k_2 y^2 \sin^2 30°$$

i.e., $$k_{eq} = \frac{3}{4} k_1 + \frac{1}{4} k_2$$

with $$k_1 = \frac{A_1 E_1}{l_1} = \frac{\frac{\pi}{4}(10^2 - 9.5^2)(30 \times 10^6)}{100} = 2.297295 \times 10^6 \text{ lb/in}$$

and $$k_2 = \frac{A_2 E_2}{l_2} = \frac{\frac{\pi}{4}(7^2 - 6.5^2)(30 \times 10^6)}{75} = 2.12058 \times 10^6 \text{ lb/in}$$

$$\therefore\ k_{eq} = \frac{3}{4}(2.297295 \times 10^6) + \frac{1}{4}(2.12058 \times 10^6)$$
$$= 2.25311625 \times 10^6 \text{ lb/in}$$

Similarly, the equivalent damping constant can be found as (using equivalence of kinetic energies):

$$c_{eq} = \frac{3}{4} c_1 + \frac{1}{4} c_2 = \frac{3}{4}(0.4) + \frac{1}{4}(0.3) = 0.375 \text{ lb-sec/in.}$$

1.47 stainless steel: $E = 30 \times 10^6$ lb/in^2, $G = 11.5 \times 10^6$ lb/in^2

For each tube:

$D = 0.30''$, $d = 0.29''$, $l = 50''$

$$\text{Axial stiffness} = \frac{AE}{l} = \frac{\pi}{4}(D^2 - d^2)\frac{E}{l}$$

$$= \frac{\pi}{4}(0.30^2 - 0.29^2)\left(\frac{30 \times 10^6}{50}\right) = 2780.316 \text{ lb/in} = k_a$$

Torsional stiffness $= \dfrac{\pi G}{32\,l}\left(D^4 - d^4\right)$

$$= \frac{\pi\,(11.5\times10^6)}{32\,(50)}\left(0.30^4 - 0.29^4\right) = 23.1942 \text{ lb-in/rad} = k_t$$

For heat exchanger with 6 tubes:

Axial stiffness $= 6\,k_a = 16{,}681.896$ lb/in

Torsional stiffness $= 6\,k_t = 139.1652$ lb-in/rad

1.48 Assume small angles θ_1 and θ_2; $\quad \theta_2 = \left(\dfrac{p_1}{p_2}\right)\theta_1$

x_1 = horizontal displacement of C.G. of mass $m_1 = \theta_1 r_1$

x_2 = vertical displacement of C.G. of mass $m_2 = \theta_2 r_2 = p_1\theta_1 r_2/p_2$

y_1 = horizontal displacement of springs k_1 and $k_2 = \theta_1(r_1 + l_1)$

y_2 = vertical displacement of springs k_3 and $k_4 = \theta_2 l_2 = p_1 l_2 \theta_1/p_2$

Equivalence of kinetic energies gives

$$\frac{1}{2}J_{eq}(\dot\theta_1)^2 = \frac{1}{2}J_1(\dot\theta_1)^2 + \frac{1}{2}J_2(\dot\theta_2)^2 + \frac{1}{2}m_1(\dot x_1)^2 + \frac{1}{2}m_2(\dot x_2)^2$$

$$\therefore\ J_{eq} = J_1 + J_2\,(p_1/p_2)^2 + m_1 r_1^2 + m_2 r_2^2\,(p_1/p_2)^2$$

Equivalence of potential energies gives

$$\frac{1}{2}k_{eq}\theta_1^2 = \frac{1}{2}k_{12}\,y_1^2 + \frac{1}{2}k_{34}\,y_2^2 + \frac{1}{2}k_{t1}\theta_1^2 + \frac{1}{2}k_{t2}\theta_2^2$$

with $k_{12} = k_1 + k_2$, $\quad k_{34} = k_3 k_4/(k_3 + k_4)$

$y_1 = \theta_1(r_1 + l_1)$, $\ y_2 = p_1 l_2\theta_1/p_2$ and $\theta_2 = p_1\theta_1/p_2$.

$$\therefore\ k_{eq} = (k_1 + k_2)(r_1 + l_1)^2 + \left(\frac{k_3 k_4}{k_3 + k_4}\right)\frac{p_1^2 l_2^2}{p_2^2} + k_{t1} + k_{t2}\frac{p_1^2}{p_2^2}.$$

1.49 $\theta = \dfrac{x}{b}$, $\quad x_1 = \dfrac{x\,a}{b}$.

From equivalence of kinetic energies,

$$\frac{1}{2}m_{eq}\dot x^2 = \frac{1}{2}m_1\dot x_1^2 + \frac{1}{2}m_2\dot x^2 + \frac{1}{2}J_0\dot\theta^2$$

$$m_{eq} = m_1\left(\frac{a}{b}\right)^2 + m_2 + J_0\left(\frac{1}{b}\right)^2$$

(1.50) Let $\dot{\theta}_i$ = angular velocity of the motor (input)

Angular velocities of different gear sets are:

J_{motor}, J_1	J_2, J_3	J_4, J_5	$\cdots$	J_{2N}, J_{load}
$\dot{\theta}_i$	$\dot{\theta}_i\left(\frac{n_1}{n_2}\right)$	$\dot{\theta}_i\left(\frac{n_1}{n_2}\,\frac{n_3}{n_4}\right)$		$\dot{\theta}_i\left(\frac{n_1}{n_2}\,\frac{n_3}{n_4}\cdots\frac{n_{2N-1}}{n_{2N}}\right)$

Equivalence of kinetic energies gives

$$\frac{1}{2}J_{eq}\,\dot{\theta}_i^2 = \frac{1}{2}J_{motor}\,\dot{\theta}_i^2 + \frac{1}{2}\sum_{k=1}^{2N} J_k\,\dot{\theta}_k^2 + \frac{1}{2}J_{load}\,\dot{\theta}_{load}^2$$

$$\therefore J_{eq} = (J_{motor} + J_1) + (J_2 + J_3)\left(\frac{n_1}{n_2}\right)^2 + (J_4 + J_5)\left(\frac{n_1}{n_2}\,\frac{n_3}{n_4}\right)^2 + \cdots + (J_{2N} + J_{load})\left(\frac{n_1}{n_2}\,\frac{n_3}{n_4}\cdots\frac{n_{2N-1}}{n_{2N}}\right)^2$$

(1.51) Equivalence of kinetic energies gives

$$\frac{1}{2}J_{eq}\,\dot{\theta}_1^2 = \frac{1}{2}J_1\,\dot{\theta}_1^2 + \frac{1}{2}J_2\,\dot{\theta}_2^2 \qquad \text{where} \qquad \dot{\theta}_2 = \dot{\theta}_1\left(\frac{n_1}{n_2}\right)$$

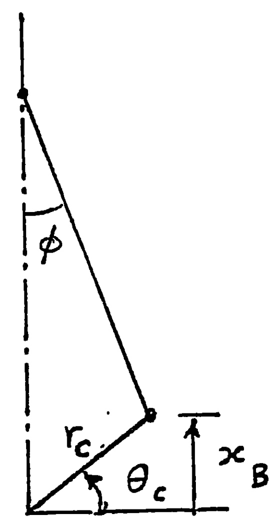
$$J_{eq} = J_1 + J_2\left(\frac{n_1}{n_2}\right)^2$$

(1.52) When point A moves by distance $x = x_h$, the walking beam rotates by the angle $\theta_b = \dfrac{x_h}{\ell_3}$.

This corresponds to a linear motion of point B: $x_B = \theta_b\,\ell_2 = \dfrac{x_h\,\ell_2}{\ell_3}$

and the angular rotation of crank can be found from the relation:

$$x_B = r_c \sin\theta_c + \ell_4 \cos\phi = r_c \sin\theta_c + \ell_4\sqrt{1 - \frac{r_c^2}{\ell_4^2}\sin^2\theta_c}$$



For large values of ℓ_4 compared to r_c and for small values of x and θ_c, we have

$$x_B \approx r_c \sin\theta_c = r_c\,\theta_c \text{ or } \theta_c = \frac{x_B}{r_c} = \frac{x_h\,\ell_2}{\ell_3\,r_c}$$

The kinetic energy of the system can be expressed as

$$T = \frac{1}{2}m_h\,\dot{x}_h^2 + \frac{1}{2}J_b\,\dot{\theta}_b^2 + \frac{1}{2}J_c\,\dot{\theta}_c^2$$

Equating this to $T = \frac{1}{2}m_{eq}\,\dot{x}^2 = \frac{1}{2}m_{eq}\,\dot{x}_h^2$, we obtain

$$m_{eq} = m_h + \frac{J_b}{\ell_3^2} + J_c\left(\frac{\ell_2}{\ell_3\,r_c}\right)^2.$$

1.53 When mass m is displaced by x, the bell crank lever rotates by the angle $\theta_b = \frac{x}{\ell_1}$. This makes the center of the sphere displace by $x_s = \theta_b\,\ell_2$. Since the sphere rotates with out slip, it rotates by an angle

$$\theta_s = \frac{x_s}{r_s} = \frac{\theta_b\,\ell_2}{r_s} = \frac{x\,\ell_2}{\ell_1\, r_s}$$

The kinetic energy of the system can be expressed as

$$T = \frac{1}{2} m \dot{x}^2 + \frac{1}{2} J_0 \dot{\theta}^2 + \frac{1}{2} J_s \dot{\theta}_s^2 + \frac{1}{2} m_s \dot{x}_s^2$$
$$= \frac{1}{2} m \dot{x}^2 + \frac{1}{2} J_0 \left(\frac{\dot{x}}{\ell_1}\right)^2 + \frac{1}{2}\left(\frac{2}{5} m_s r_s^2\right) \dot{x}^2 \left(\frac{\ell_2}{\ell_1 r_s}\right)^2 + \frac{1}{2} m_s \left(\frac{\dot{x}\,\ell_2}{\ell_1}\right)^2$$

since for a sphere, $J_s = \frac{2}{5}\, m_s\, r_s^2$. Equating this to $T = \frac{1}{2}\, m_{eq}\, \dot{x}^2$, we obtain

$$m_{eq} = m + J_0\, \frac{1}{\ell_1^2} + \frac{7}{5}\, m_s\, \frac{\ell_2^2}{\ell_1^2}$$

1.54

When the angular position of the crank is θ from x-axis, the angular position of connecting rod ϕ, shown in Fig. 1.101, is given by

$$r \sin\theta = \delta + l \sin\phi \tag{1}$$

The x- and y- coordinates of piston (x_p, y_p) are given by

$$x_p = r\cos\theta + l\cos\phi \tag{2}$$

$$y_p = \delta \tag{3}$$

The x- and y- coordinates of the center of mass of the connecting rod (x_c, y_c) can be expressed as

$$x_c = r\cos\theta + l_1\cos\phi \tag{4}$$

$$y_c = r\sin\theta - l_1\sin\phi \tag{5}$$

The x- and y- coordinates of the center of mass of the crank are given by

$$x_r = \frac{r}{2}\cos\theta \tag{6}$$

$$y_r = \frac{r}{2}\sin\theta \tag{7}$$

Differentiation of Eqs. (1) – (5) with respect to time yields

$$r\cos\theta\,\dot\theta = l\cos\phi\,\dot\phi \quad \text{or} \quad \dot\phi = \frac{r}{l}\,\frac{\cos\theta}{\cos\phi}\,\dot\theta \tag{8}$$

$$\dot x_p = -r\sin\theta\,\dot\theta - l\sin\phi\,\dot\phi \tag{9}$$

$$\dot y_p = 0 \tag{10}$$

$$\dot x_c = -r\sin\theta\,\dot\theta - l_1\sin\phi\,\dot\phi \tag{11}$$

$$\dot y_c = r\cos\theta\,\dot\theta - l_1\cos\phi\,\dot\phi \tag{12}$$

Using Eq. (8), Eq. (9) can be expressed as

$$\dot x_p = -r\sin\theta\,\dot\theta - l\sin\phi\,\frac{r}{l}\,\frac{\cos\theta}{\cos\phi}\,\dot\theta$$

$$= -r\dot\theta\,(\sin\theta + \cos\theta\tan\phi) \tag{13}$$

Similarly, using Eq. (8), Eqs. (11) and (12) can be expressed as

$$\dot{x}_c = -r\dot{\theta}\left(\sin\theta + \frac{l_1}{l}\cos\theta\tan\phi\right) \tag{14}$$

$$\dot{y}_c = r\dot{\theta}\,\frac{l_2}{l}\cos\theta \tag{15}$$

Finally, differentiation of Eqs. (6) and (7) yields

$$\dot{x}_r = -\frac{r}{2}\sin\theta\,\dot{\theta} \tag{16}$$

$$\dot{y}_r = \frac{r}{2}\cos\theta\,\dot{\theta} \tag{17}$$

The kinetic energy of the system (T) can be expressed as

$$T = \frac{1}{2}m_r(\dot{x}_r^2 + \dot{y}_r^2) + \frac{1}{2}J_r\dot{\theta}^2 + \frac{1}{2}m_c(\dot{x}_c^2 + \dot{y}_c^2) + \frac{1}{2}J_c\dot{\phi}^2 + \frac{1}{2}m_p(\dot{x}_p^2 + \dot{y}_p^2)$$

$$= \frac{1}{2}m_r\frac{r^2}{4}\dot{\theta}^2 + \frac{1}{2}J_r\dot{\theta}^2 + \frac{1}{2}m_c\left\{\left(\sin^2\theta + \frac{l_1^2}{l^2}\cos^2\theta.\tan^2\phi + 2\frac{l_1}{l}\sin\theta\cos\theta\tan\phi\right)r^2\dot{\theta}^2 + \frac{l_2^2}{l^2}\cos^2\theta\, r^2\dot{\theta}^2\right\} + \frac{1}{2}J_c\dot{\phi}^2 + \frac{1}{2}m_p\left(r^2\sin^2\theta\,\dot{\theta}^2 + l^2\sin^2\phi\,\dot{\phi}^2 + 2rl\sin\theta\sin\phi\,\dot{\theta}\,\dot{\phi}\right) \tag{18}$$

If the equivalent rotatory inertia of the whole system about the point O is denoted as J_{eq}, the kinetic energy of the system (T) can be written as

$$T = \frac{1}{2}J_{eq}\dot{\theta}^2 \tag{19}$$

By equating Eqs. (18) and (19), the equivalent rotatory inertia of the offset slider crank mechanism can be expressed as

$$J_{eq} = \frac{1}{4}m_r r^2 + J_r + m_c\left\{\left(\sin^2\theta + \frac{l_1^2}{l^2}\cos^2\theta\tan^2\phi + \frac{l_1}{l}\sin 2\theta\tan\phi\right)r^2 + \frac{l_2^2}{l^2}\cos^2\theta\, r^2\right\} + J_c\frac{\dot{\phi}^2}{\dot{\theta}^2} + m_p\left(\sin^2\theta\, r^2 + l^2\sin^2\phi\frac{\dot{\phi}^2}{\dot{\theta}^2} + 2rl\sin\theta\sin\phi\frac{\dot{\phi}}{\dot{\theta}}\right) \tag{20}$$

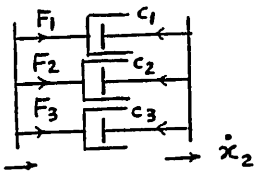
In view of Eq. (8), Eq. (20) can be rewritten as

$$J_{eq} = \frac{1}{4} m_r r^2 + J_r + m_c r^2 \left\{ \left(\sin^2\theta + \frac{l_1^2}{l^2} \cos^2\theta \tan^2\phi + \frac{l_1}{l} \sin 2\theta \tan\phi \right) + \frac{l_2^2}{l^2} \cos^2\theta \right\} + J_c \frac{r^2}{l^2} \frac{\cos^2\theta}{\cos^2\phi} + m_p r^2 \left(\sin^2\theta + \sin^2\phi \frac{\cos^2\theta}{\cos^2\phi} + 2 \sin\theta \sin\phi \frac{\cos\theta}{\cos\phi} \right)$$

or

$$J_{eq} = \frac{1}{4} m_r r^2 + J_r + m_c r^2 \left\{ \left(\sin^2\theta + \frac{l_1^2}{l^2} \cos^2\theta \tan^2\phi + \frac{l_1}{l} \sin 2\theta \tan\phi \right) + \frac{l_2^2}{l^2} \cos^2\theta \right\} + \frac{J_c r^2}{l^2} \frac{\cos^2\theta}{\cos^2\phi} + m_p r^2 \left(\sin^2\theta + \cos^2\theta \tan^2\phi + \sin 2\theta \tan\phi \right) \tag{21}$$

1.55 (a)

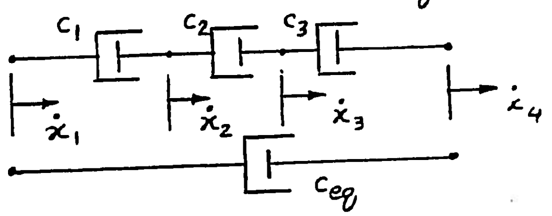


F_i = damping force of $c_i = c_i(\dot{x}_2 - \dot{x}_1)$; $i = 1,2,3$

F_{eq} = damping force of $c_{eq} = c_{eq}(\dot{x}_2 - \dot{x}_1)$
$\equiv F_1 + F_2 + F_3$

$\therefore \quad c_{eq} = c_1 + c_2 + c_3$

(b)



$F_1 = c_1(\dot{x}_2 - \dot{x}_1)$

$F_2 = c_2(\dot{x}_3 - \dot{x}_2)$

$F_3 = c_3(\dot{x}_4 - \dot{x}_3)$

$$\dot{x}_4 - \dot{x}_1 = \dot{x}_4 - \dot{x}_3 + \dot{x}_3 - \dot{x}_2 + \dot{x}_2 - \dot{x}_1$$

$$\frac{F_{eq}}{c_{eq}} = \frac{F_3}{c_3} + \frac{F_2}{c_2} + \frac{F_1}{c_1}$$

since $F_{eq} = F_1 = F_2 = F_3$, $\quad \dfrac{1}{c_{eq}} = \dfrac{1}{c_1} + \dfrac{1}{c_2} + \dfrac{1}{c_3}$

(c) Equating the energies dissipated in a cycle,

$$\pi c_{eq} \omega X_1^2 = \pi c_1 \omega X_1^2 + \pi c_2 \omega X_2^2 + \pi c_3 \omega X_3^2$$

where $X_1 = \theta l_1$, $X_2 = \theta l_2$ and $X_3 = \theta l_3$

$$\therefore \quad c_{eq} = c_1 + c_2\left(\frac{l_2}{l_1}\right)^2 + c_3\left(\frac{l_3}{l_1}\right)^2$$

(d) Equating the energies dissipated in a cycle,

$$\pi c_{teq} \omega \theta_1^2 = \pi c_{t1} \omega \theta_1^2 + \pi c_{t2} \omega \theta_2^2 + \pi c_{t3} \omega \theta_3^2$$

where $\theta_2 = \theta_1\left(\frac{n_1}{n_2}\right)$ and $\theta_3 = \theta_1\left(\frac{n_1}{n_3}\right)$.

$$\therefore \quad c_{teq} = c_{t1} + c_{t2}\left(\frac{n_1}{n_2}\right)^2 + c_{t3}\left(\frac{n_1}{n_3}\right)^2.$$

1.56

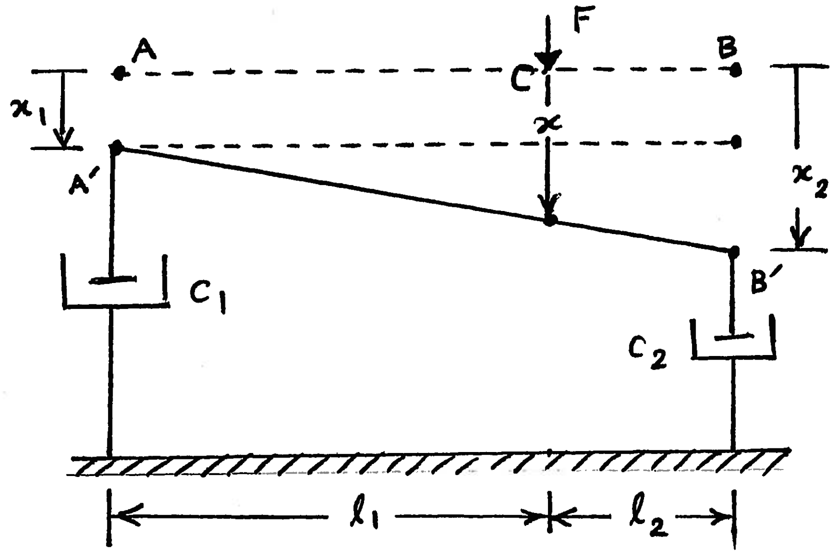


Fig. (a)

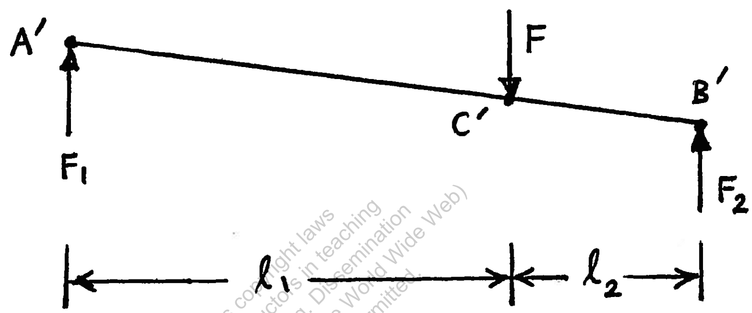


Fig. (b)

Let x_1, x_2, x = displacements of points A, B, C in Fig. (a)

F_i = force of damper i ; $i = 1, 2$

From Fig. (a),

$$x = x_1 + \frac{l_1}{l_1+l_2}(x_2 - x_1) = \frac{l_2}{l_1+l_2}x_1 + \frac{l_1}{l_1+l_2}x_2 \quad (1)$$

and hence

$$\dot{x} = \frac{l_2}{l_1+l_2}\dot{x}_1 + \frac{l_1}{l_1+l_2}\dot{x}_2 \quad (2)$$

For vertical force equilibrium (Fig. b):

$$F = F_1 + F_2 \quad (3)$$

For moment equilibrium about point C′ (Fig. b):

$$F_2 l_2 = F_1 l_1 \quad (4)$$

Eqs. (3) and (4) give

$$F_1 = \frac{F l_2}{l_1+l_2}, \quad F_2 = \frac{F l_1}{l_1+l_2} \quad (5)$$

Velocities experienced by dampers:

$$\dot{x}_1 = \frac{F_1}{c_1} = \frac{F l_2}{c_1(l_1+l_2)} \qquad (6)$$

$$\dot{x}_2 = \frac{F_2}{c_2} = \frac{F l_1}{c_2(l_1+l_2)} \qquad (7)$$

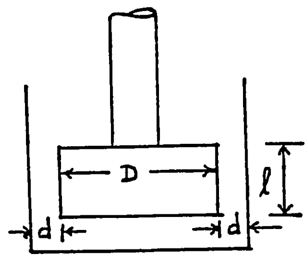
Velocity of point C (or force F) can be found using Eqs. (6) and (7) in Eq. (2):

$$\dot{x} = \frac{F}{c_1} \frac{l_2^2}{(l_1+l_2)^2} + \frac{F}{c_2} \frac{l_1^2}{(l_1+l_2)^2} \qquad (8)$$

The equivalent damping constant of the system in the direction of x, c_e, is given by

$$c_e = \frac{F}{\dot{x}} = \frac{(l_1+l_2)^2 c_1 c_2}{l_1^2 c_1 + l_2^2 c_2} \qquad (9)$$

(1.57) Damping constant desired = c = 1 lb-sec/in, viscosity of the fluid = $\mu = 4\ \mu$ reyn $= 4\ (10^{-6})$ lb—sec/in^2.



$$c = \mu \left\{ \frac{3\ \pi\ D^3\ \ell\ (1 + \frac{2\ d}{D})}{4\ d^3} \right\} \qquad (1)$$

Assuming $x = D/d$ as the unknown with $\ell = 2$ in, Eq. (1) can be written as

$$c = \mu \left(\frac{3\ \pi\ \ell\ x^3}{4} \right) (1 + \frac{2}{x}) \quad \text{or} \quad 1 = (4\ (10^{-6}))\ (\frac{3\ \pi\ (2)}{4})\ x^3\ (1 + \frac{2}{x}) \qquad (2)$$

This gives $x^3 + 2\ x^2 - 53{,}051.52 = 0$
Using a trial and error procedure, the solution of this cubic equation can be found as $x \approx 36.92$. Using $D = 3$ in, we get $d = 3/36.92 = 0.08126$ in.

(1.58) $c = \mu \left\{ \frac{3\pi D^3 \ell}{4 d^3} \left(1 + 2\frac{d}{D}\right) \right\};$

D = diameter of piston

ℓ = axial length of piston

d = radial clearance

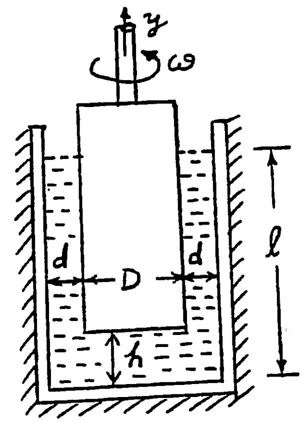
$\mu = 45\ \mu$ reynolds
(from Shigley's Mechanical Engineering Design)

Let $d = 0.001''$, $D = 2.4''$ and above equation gives

$$10^5 = (45 \times 10^{-6}) \left\{ \frac{3\pi (2.4)^3 \ell}{4 (0.001)^3} \left(1 + \frac{2 \times 0.001}{2.4}\right) \right\}$$

$\therefore\ \ell = 0.6817''$.

1.59 Tangential velocity of inner cylinder $= \frac{D}{2}\omega$



For small d, rate of change of velocity of fluid is $\dfrac{dv}{dr} = \dfrac{\frac{D}{2}\omega}{d}$

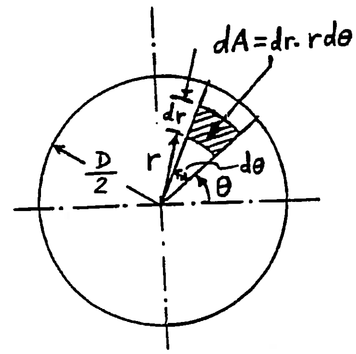
shear stress between cylinders is

$$\tau = \mu \frac{dv}{dr} = \mu \frac{D\omega}{2d}$$

and shear force is

$$F = \tau \cdot \text{Area} = \tau\, \pi D (l - h) = \frac{\pi \mu D^2 \omega (l-h)}{2d}$$

Torque developed $= M_{t1} = F \cdot \frac{D}{2}$



For small h, rate of change of velocity of fluid in vertical direction is

$$\frac{dv}{dy} = \frac{r\omega}{h}$$

Shear stress is $\tau = \mu \dfrac{dv}{dy} = \dfrac{\mu r \omega}{h}$

Force on area $dA = dF = \tau\, dA$

Torque between bottom surfaces of cylinders is

$$M_{t2} = \iint_{\text{area}} dM_{t2} \cdot dA \quad \text{where } dM_{t2} = dF \cdot r = \frac{\mu r^3 \omega}{h}\, dr\, d\theta$$

i.e., $$M_{t2} = \frac{\mu\omega}{h} \int_{r=0}^{D/2} \int_{\theta=0}^{2\pi} r^3 \cdot dr\, d\theta = \frac{\mu \omega \pi D^4}{64 h}$$

$$\text{Total torque} = M_t = M_{t1} + M_{t2} = \frac{\pi \mu D^3 \omega (l-h)}{4d} + \frac{\pi \mu \omega D^4}{64 h}$$

Expressing M_t as $c_t\, v = c_t\, \omega D/2$, we get damping constant:

$$c_t = \frac{\pi \mu D^2 (l-h)}{2d} + \frac{\pi \mu D^3}{32 h}$$

1.60

$$F = 1000\,v + 400\,v^2 + 20\,v^3 \qquad (1)$$

Taylor's series expansion of Eq. (1) about the operating velocity $v^* = 10$ m/s gives the linearized damping constant (c) as [see Section 1.9.2]:

$$c = \left.\frac{dF}{dv}\right|_{v = v^*} \qquad (2)$$

For Eq. (1),

$$\left.\frac{dF}{dv}\right|_{v^*} = \left.\left(1000 + 800\,v + 60\,v^2\right)\right|_{v = v^* = 10}$$

$$= 1000 + 800(10) + 60\,(10^2) = 15000 \text{ N-s/m} \qquad (3)$$

Hence linearized damping constant is defined by

$F = c\,v$ with $c = 15000$ N-s/m.

1.61

From Problem 1·60, the linearized damping constant of the two dampers is given by $c = 15000$ N-s/m (for each). When two dampers are connected in parallel, the equivalent damping constant is given by (see section 1.9.3 and Problem 1.55):

$$c_{eq} = c_1 + c_2 = 2c = 30000 \text{ N-s/m}$$

1.62

From Problem 1.60, the linearized damping constant of each of the two dampers is given by

$c = 15000$ N-s/m.

When two dampers are connected in series, the equivalent damping constant is given by (see Section 1.9.3 and Problem 1.55):

$$\frac{1}{c_{eq}} = \frac{1}{c_1} + \frac{1}{c_2} = \frac{2}{c}$$

or

$$c_{eq} = \frac{c}{2} = \frac{15000}{2} = 7500 \text{ N-s/m}$$

1.63

Force - velocity relation of the damper:

$$F = 500\,v + 100\,v^2 + 50\,v^3 \qquad (1)$$

Linearized damping constant of the damper at the operating velocity $v^* = 5$ m/s is given by (see section 1.9.2):

$$c = \left.\frac{dF}{dv}\right|_{v=v^*} = \left.(500 + 200\,v + 150\,v^2)\right|_{v^*=5}$$

$$= 500 + 1000 + 3750 = 5250 \text{ N-s/m} \qquad (2)$$

If linearized damping constant (c) is used at an operating velocity of 10 m/s, the damping force (F) is given by

$$F = c\,v = 5250\,(10) = 52{,}500 \text{ N} \qquad (3)$$

The actual damping force given by the nonlinear damper, Eq. (1), is

$$F_{actal} = 500(10) + 100(10^2) + 50(10^3) = 65{,}000 \text{ N} \quad (4)$$

Thus the error involved in estimating the damping force is

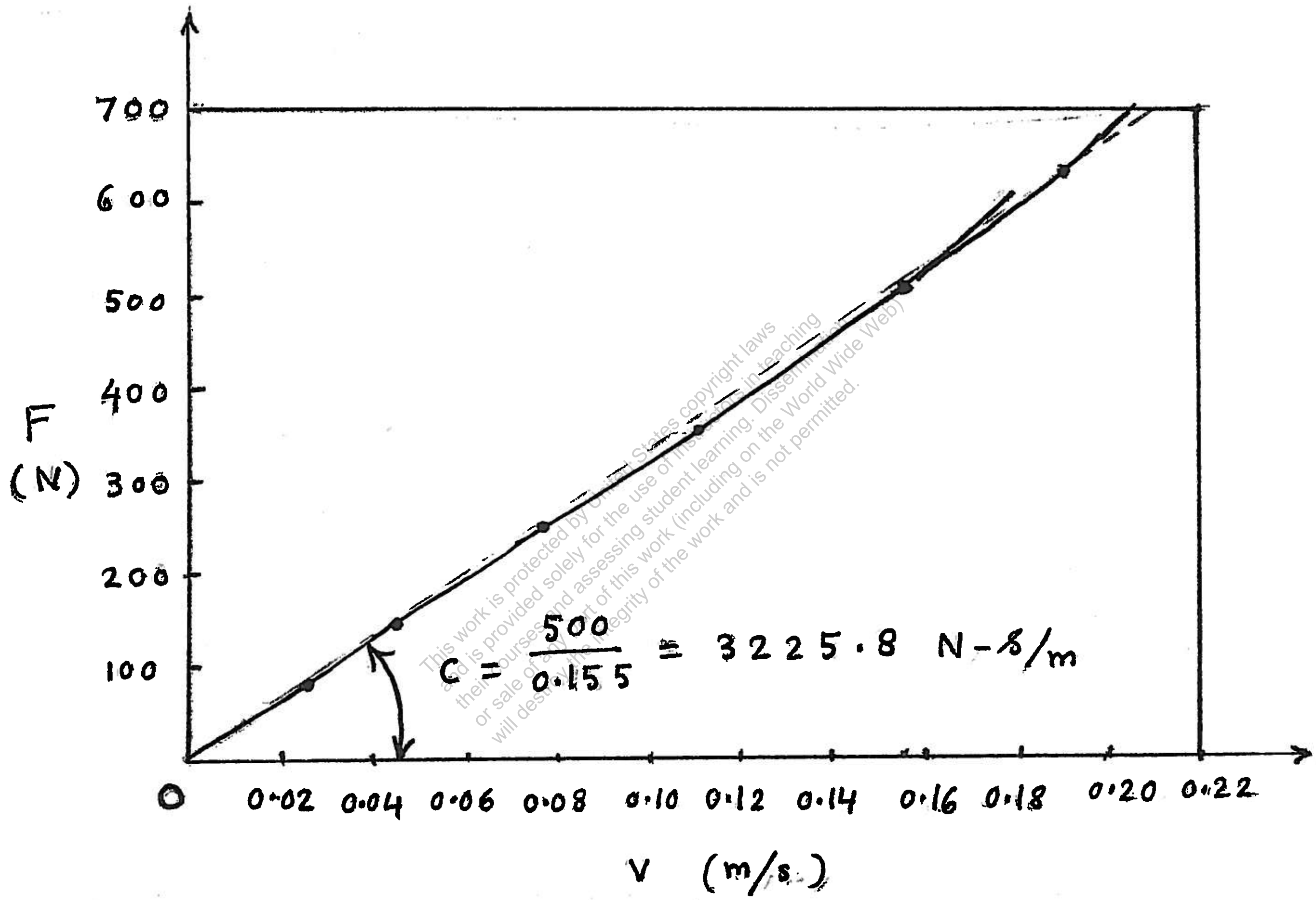
$$65{,}000 - 52{,}500 = 12{,}500 \text{ N}$$

or $\dfrac{12{,}500}{65{,}000} \times 100 = 19.23\%$ (under-estimation).

1.64

The data are plotted in a graph as shown below. The damping constant of the damper is given by the slope of the force-velocity line:

$$c = \frac{F}{v} \simeq \frac{500}{0.155} = 3{,}225.8 \text{ N-s/m}$$



1.65

Flat plates in parallel with lubricant film in between:

surface area of top plate $(A) = 0.25\ m^2$

Film thickness $(h) = 1.5\ mm = 0.0015\ m$

Viscosity of lubricant $(\mu) = 0.5\ Pa-s$

(a) Damping constant (c):

$$c = \frac{\mu A}{h} = \frac{0.5\,(0.25)}{0.0015} = 83.3333\ N\text{-}s/m$$

(b) Damping force developed when $v = 2\ m/s$:

$$F = c\,v = 83.3333\,(2) = 166.6666\ N$$

1.66

Torsional damping constant of journal bearing:

viscosity of lubricant $= \mu = 0.35$ Pa-s

Diameter of shaft $= 2R = 0.05$ m

Length of bearing $= l = 0.075$ m

Bearing clearance $= d = 0.005$ m

Rotational speed $= N = 3000$ rpm or $\omega = 314.16$ rad/s

Damping torque developed (T):

$$T = \frac{2\pi \mu R^3 l \omega}{d} = \frac{2\pi (0.35)(0.025^3)(0.075)(314.16)}{0.005}$$

$$= 0.1619 \text{ N-m}$$

Torsional damping constant (c_t):

$$c_t = \frac{T}{\omega} = \frac{0.1619}{314.16} = 0.0005153 \text{ N-m-s}$$

1.67

Torsional damping constant $= c_t = \dfrac{2\pi \mu R^3 \ell}{d}$

Damping torque developed $= T = c_t \omega = \dfrac{2\pi \mu R^3 \ell \omega}{d}$

Ranges of parameters:

$\mu = 0.35 \pm 5\%$ Pa-s $\Rightarrow (0.3325, 0.3675)$

$R = 0.025 \pm 5\%$ m $\Rightarrow (0.02375, 0.02625)$

$\ell = 0.075 \pm 5\%$ m $\Rightarrow (0.07125, 0.07875)$

$d = 0.005 \pm 5\%$ m $\Rightarrow (0.00475, 0.00525)$

$N = 3000 \pm 5\%$ rpm or

$\omega = 314.16 \pm 5\%$ rad/s $\Rightarrow (298.452, 329.868)$

By using all possible combinations of lower and upper bound values of the five parameters (a MATLAB program is written for this purpose), the ranges of c_t and T are found to be

$c_t \Rightarrow (0.0003798, 0.0006924)$ N-m-s

$T \Rightarrow (0.1134, 0.2284)$ N-m

These correspond to percent total fluctuations of

$$c_t = \frac{0.0006924 - 0.0003798}{(c_t)_{mean} = 0.0005153} \times 100 = 60.6637\%$$

$$T = \frac{0.2284 - 0.1134}{(T)_{mean} = 0.1619} \times 100 = 71.0315\%$$

MATLAB program and output are shown on following page.

```
clear all; close all; clc; format long g

mu_mean = 0.35;
R_mean = 0.025;
l_mean = 0.075;
d_mean = 0.005;
N_mean = 3000;
w_mean = 314.16;
variation = 0.05;
mu = [mu_mean*(1-variation),mu_mean*(1+variation)];
R = [R_mean*(1-variation),R_mean*(1+variation)];
l = [l_mean*(1-variation),l_mean*(1+variation)];
d = [d_mean*(1-variation),d_mean*(1+variation)];
% N = [N_mean*(1-variation),N_mean*(1+variation)];
w = [w_mean*(1-variation),w_mean*(1+variation)];

for i1 = 1:length(mu)
    for i2 = 1:length(R)
        for i3 = 1:length(l)
            for i4 = 1:length(d)
                  for i5 = 1:length(w)
                    Ct(i1,i2,i3,i4,i5) = 2*pi*mu(i1)*R(i2)^3*l(i3)/d
(i4);
                    T(i1,i2,i3,i4,i5) = 2*pi*mu(i1)*R(i2)^3*l(i3)/d(i4)
*w(i5);
                end
            end
        end
    end
end

Min_Ct = min(min(min(min(min(Ct(:,:,:,:,:))))))
Max_Ct = max(max(max(max(max(Ct(:,:,:,:,:))))))
Min_T = min(min(min(min(min(T(:,:,:,:,:))))))
Max_T = max(max(max(max(max(T(:,:,:,:,:))))))


          Min_Ct =

                0.000379828829490285


          Max_Ct =

                0.000692439904555133


          Min_T =

                   0.113360673819034


          Max_T =

                   0.228413766435793

          EDU>>
```

1.68

Assumptions made:

1. viscous fluid is incompressible.
2. velocity of piston is small.
3. Mass flow rate of fluid through the orifice is known in terms of the pressure difference across the orifice:

Mass flow rate $(Q) = \dfrac{\sqrt{\Delta p}}{\alpha}$ (1)

where α is a constant, known from experiments [see: B.R. Munson, D.F. Young, T.H. Okiishi and W.W. Huebsch, "Fundamentals of Fluid Mechanics", 6th Edition, John Wiley, 2009].

The volume flow rate of the fluid through the orifice can be expressed as

$$\frac{Q}{\rho} = A\, v \qquad (2)$$

where ρ = density of fluid, A = area of piston surface and v = velocity of piston. In view of Eq. (1), Eq. (2) can be expressed as

$$\frac{\sqrt{\Delta p}}{\rho\,\alpha} = A\, v \quad \text{or} \quad v = \frac{\sqrt{\Delta p}}{\alpha\,\rho\, A} \qquad (3)$$

Since the piston velocity is assumed to be small, the force on the piston (F) can be found as

$$F = \Delta p \cdot A \quad \text{or} \quad \Delta p = \frac{F}{A} \qquad (4)$$

Using Eq. (4) in Eq. (3), we obtain

$$v = \frac{\sqrt{F}}{\alpha\,\rho\, A^{3/2}} \quad \text{or} \quad F = \alpha^2 \rho^2 A^3 v^2 \qquad (5)$$

Thus the force - velocity relation is given by

$$F = c\, v^2 \qquad (6)$$

where c is the damping constant ($c = \alpha^2 \rho^2 A^3$).

Note: 1. The damping force (F) is proportional to the square of velocity. Hence the damper is nonlinear.

2. The damping force - velocity relation, Eq. (6), can be linearized about any operating velocity (v^*) to find an approximate linear damping constant.

1.69

$F = a\dot{x} + b\dot{x}^2 = 5\dot{x} + 0.2\dot{x}^2$

$F(\dot{x}) \approx F(\dot{x}_0) + \frac{dF}{d\dot{x}}\Big|_{\dot{x}_0}(\dot{x} - \dot{x}_0)$

At $\dot{x}_0 = 5$ m/s, $F(\dot{x}_0) = 5\,(5) + 0.2\,(25) = 30$ N, $\frac{dF}{d\dot{x}}\Big|_{\dot{x}_0} = (5 + 0.4\,\dot{x})\Big|_5 = 7$ and hence

$F(\dot{x}) = 30 + 7\,(\dot{x} - 5) = 7\,\dot{x} - 5.$

Thus the linearized damping constant is given by $F(\dot{x}) \approx 7\,\dot{x} = c_{eq}\,\dot{x}$ or $c_{eq} = 7$ N–s/m.

1.70

Damping constant due to skin friction drag is:

$$c = 100\,\mu\,\ell^2\,d \qquad (1)$$

Damping constant of a plate-type damper is:

$$c_p = \frac{\mu\,A}{h} \qquad (2)$$

where A = area of plates and h = distance between the plates. If the area of plates (A) in Fig. 1.42 is taken to be same as the area of the plate shown in Fig. 1.107, we have $A = \ell\,d$. Equating (1) and (2) gives

$$100\,\mu\,\ell^2\,d = \frac{\mu\,\ell\,d}{h} \qquad (3)$$

from which the clearance between the plates can be determined as $h = \frac{1}{100\,\ell}$.

1.71

$$c = \frac{6\,\pi\,\mu\,\ell}{h^3}\left\{\left(a - \frac{h}{2}\right)^2 - r^2\right\}\left(\frac{a^2 - r^2}{a - \frac{h}{2}} - h\right)$$

When $\mu = 0.3445$ Pa-s, $\ell = 0.1$ m, $h = 0.001$ m, $a = 0..02$ m, and $r = 0.005$ m:

$$c = \frac{6\,\pi\,(0.3445)\,(0.1)}{(10^{-3})^3}\left\{(0.02 - 0.0005)^2 - 0.005^2\right\}\left(\frac{0.02^2 - 0.005^2}{0.02 - 0.0005} - 0.001\right)$$

$$= 4{,}205.6394 \text{ N–s/m}$$

1.72

$$c = \frac{6\pi\mu\, l}{h^3}\left[\left(a - \frac{h}{2}\right)^2 - r^2\right]\left[\frac{a^2 - r^2}{a - \frac{h}{2}} - h\right]$$

Basic data: $l = 10$ cm, $h = 0.1$ cm, $a = 2$ cm, $r = 0.5$ cm, $\mu = 0.3445$

Damping constant with basic data:

$c = 4{,}205.6230$ N-s/m

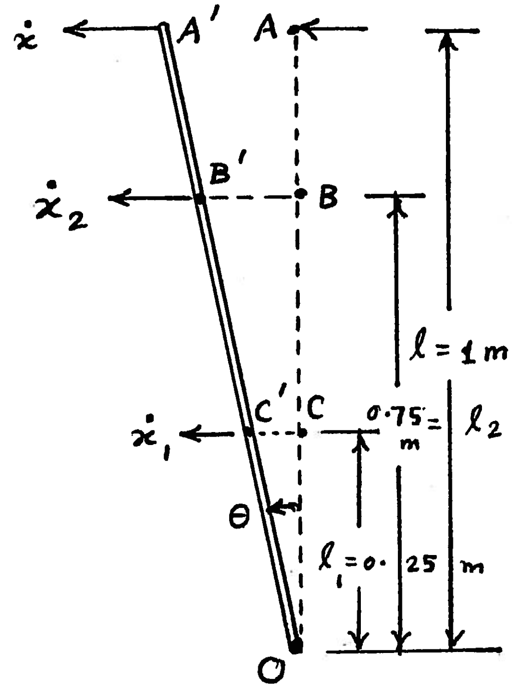
(a) r changed to 1 cm; new $c = 2{,}617.7920$ N-s/m

(b) h changed to 0.05 cm; new $c = 35{,}060.8910$ N-s/m

(c) a changed to 4 cm; new $c = 38{,}754.5860$ N-s/m

1.73

Let linear velocity of point A be $\dot{x}$. If $\dot{\theta}$ is the angular velocity of the bar about the pivot point O, the linear velocities of points A, B and C are given by



$$\dot{x} = l\dot{\theta} = \dot{\theta}$$

$$\dot{x}_2 = l_2 \dot{\theta} = 0.75\ \dot{\theta}$$

$$\dot{x}_1 = l_1 \dot{\theta} = 0.25\ \dot{\theta}$$

Damping forces at points B and C are given by

$$F_2 = c_2 \dot{x}_2 = 0.75\, c_2 \dot{\theta} = 0.75(15)\dot{\theta} = 11.25\ \dot{\theta}$$

$$F_1 = c_1 \dot{x}_1 = 0.25\, c_1 \dot{\theta} = 0.25(10)\ \dot{\theta} = 2.50\ \dot{\theta}$$

Assuming equivalent damping constant at point A as c_{eq}, the force F can be expressed as

$$F = c_{eq}\dot{x} = c_{eq}\dot{\theta}$$

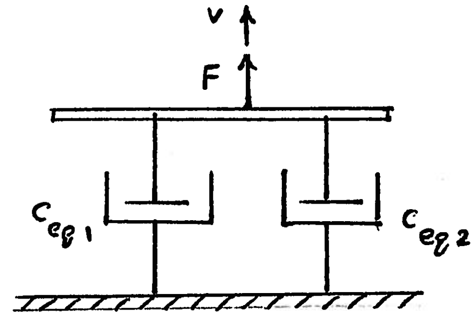
Moment equilibrium equation about the pivot point O gives

$$F\,l = F_1 l_1 + F_2 l_2$$

or $$c_{eq}\dot{\theta}(1) = 2.5\ \dot{\theta}(0.25) + 11.25\ \dot{\theta}(0.75)$$

or $$c_{eq} = 9.0625\ \text{N-s/m}$$

1.74



For two dampers in series, the equivalent damping constant is given by

$$\frac{1}{c_{eq1}} = \frac{1}{c_1} + \frac{1}{c_1} = \frac{2}{c_1}$$

or $$c_{eq1} = \frac{c_1}{2}$$

For two dampers in parallel, the equivalent damping constant is given by

$$c_{eq2} = c_2 + c_2 = 2c_2$$

Thus the system can be replaced by the two equivalent dampers in parallel as shown in the figure above. The overall equivalent damping constant is given by

$$c_{eq} = c_{eq1} + c_{eq2} = \frac{c_1}{2} + 2c_2$$

so that

$$F = c_{eq} v$$

(1.75) $\vec{x} = 5 + 2i = Ae^{i\theta} = A\cos\theta + i\,A\sin\theta$

$A\cos\theta = 5$

$A\sin\theta = 2$

$A = \sqrt{(A\cos\theta)^2 + (A\sin\theta)^2} = \sqrt{5^2 + 2^2} = 5.3852$

$\theta = \tan^{-1}\left(\dfrac{A\sin\theta}{A\cos\theta}\right) = \tan^{-1}\left(\dfrac{2}{5}\right) = 21.8014^\circ$

(1.76) $\vec{x}_1 = 1 + 2i = a_1 + a_2 i$, $\vec{x}_2 = 3 - 4i = b_1 + b_2 i$

$\vec{x} = \vec{x}_1 + \vec{x}_2 = (a_1 + b_1) + i(a_2 + b_2) = 4 - 2i$

$= Ae^{i\theta} = A\cos\theta + i\,A\sin\theta$

$A = \sqrt{4^2 + (-2)^2} = 4.4721$

$\theta = \tan^{-1}\left(\dfrac{-2}{4}\right) = -26.5651^\circ$

(1.77) $z_1 = (3 - 4i)$, $z_2 = (1 + 2i)$

$z = z_1 - z_2 = (3 - 4i) - (1 + 2i) = 2 - 6i = A e^{i\theta}$

where $A = \sqrt{2^2 + (-6)^2} = 6.3246$ and $\theta = \tan^{-1}\left(\dfrac{-6}{2}\right) = \tan^{-1}(-3) = -1.2490$ rad

---

(1.78) $z_1 = 1 + 2i$, $z_2 = 3 - 4i$

$z = z_1 z_2 = (1 + 2i)(3 - 4i) = 11 + 2i = A e^{i\theta}$

where $A = \sqrt{11^2 + 2^2} = 11.1803$ and $\theta = \tan^{-1}(2/11) = 0.1798$ rad

---

(1.79) $z = \dfrac{z_1}{z_2} = \dfrac{1 + 2i}{3 - 4i} = \dfrac{(1 + 2i)(3 + 4i)}{(3 - 4i)(3 + 4i)} = \dfrac{-5 + 10i}{25} = -0.2 + 0.4i = A e^{i\theta}$

where $A = \sqrt{(-0.2)^2 + (0.4)^2} = 0.4472$

and $\theta = \tan^{-1}\left(\dfrac{-0.4}{0.2}\right) = \tan^{-1}(-2) = -1.1071$ rad

1.80 $x(t) = X \cos \omega t\,, \quad y(t) = Y \cos(\omega t + \phi)$

(a) $\dfrac{x^2}{X^2} = \cos^2 \omega t, \quad \dfrac{y^2}{Y^2} = \cos^2(\omega t + \phi),$

$$2\,\frac{x\,y}{X\,Y} \cos\phi = 2 \cos\omega t \cos(\omega t + \phi) \cos\phi$$

$$\frac{x^2}{X^2} + \frac{y^2}{Y^2} - 2\,\frac{x\,y}{X\,Y}\cos\phi$$

$$= \cos^2 \omega t + \cos^2(\omega t + \phi) - 2 \cos\omega t \cos\phi \cos(\omega t + \phi) \qquad (1)$$

Noting that $\cos^2 \alpha = \dfrac{1}{2}(1 + \cos 2\alpha)$, Eq. (1) can be rewritten as

$$\frac{x^2}{X^2} + \frac{y^2}{Y^2} - 2\,\frac{x\,y}{X\,Y}\cos\phi$$

$$= \frac{1}{2} + \frac{1}{2}\cos 2\omega t + \frac{1}{2} + \frac{1}{2}\cos(2\omega t + 2\phi) - 2\cos\omega t\cos\phi\cos(\omega t + \phi)$$

$$= 1 + \frac{1}{2}\left\{2\cos\frac{2\omega t + 2\omega t + 2\phi}{2}\cos\frac{2\omega t - 2\omega t - 2\phi}{2}\right\}$$
$$- 2\cos\omega t\cos\phi\cos(\omega t + \phi)$$

$$= 1 + \cos(2\omega t + \phi)\cos\phi - 2\cos\omega t\cos\phi\cos(\omega t + \phi)$$

$$= 1 + \cos(2\omega t + \phi)\cos\phi - 2\cos\phi\left\{\frac{1}{2}\left[\cos(\omega t + \phi - \omega t) + \cos(\omega t + \phi + \omega t)\right]\right\}$$

$$= 1 + \cos\phi\cos(2\omega t + \phi) - \cos\phi\left\{\cos\phi + \cos(2\omega t + \phi)\right\}$$

$$= 1 - \cos^2\phi = \sin^2\phi \qquad (2)$$

(b) When $\phi = 0$, Eq. (2) reduces to

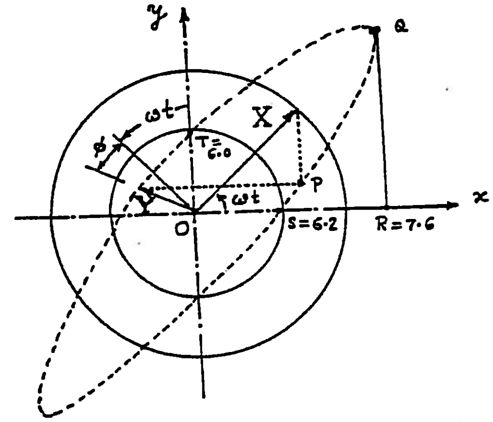
$$\frac{x^2}{X^2} + \frac{y^2}{Y^2} - 2\,\frac{x\,y}{X\,Y} = \left(\frac{x}{X} - \frac{y}{Y}\right)^2 = 0$$

which gives $X = \pm\dfrac{X}{Y}\,y$. This indicates that the locus of the resultant motion is a straight line. When $\phi = \dfrac{\pi}{2}$, Eq. (2) reduces to

$$\frac{x^2}{X^2} + \frac{y^2}{Y^2} = 1$$

which denotes an ellipse with its major and minor axes along x and y directions, respectively. When $\phi = \pi$, Eq. (2) reduces to that of a straight line as in the case of $\phi = 0$.

1.81



Equation for resultant motion:

$$\frac{x^2}{X^2}+\frac{y^2}{Y^2}-2\,\frac{x\,y}{X\,Y}\cos^2\phi=\sin^2\phi \qquad (1)$$

When $y = 0$, Eq. (1) reduces to $\frac{x^2}{X^2}=\sin^2\phi$ and hence:

$$x=\pm X\sin\phi=\pm 6.2=\text{OS in figure} \qquad (2)$$

When $x = 0$, Eq. (1) reduces to $\frac{y^2}{Y^2}=\sin^2\phi$ and hence:

$$y=\pm Y\sin\phi=\pm 6.0=\text{OT in figure} \qquad (3)$$

It can be seen that

$$OR=X\cos\phi=7.6\text{ in figure} \qquad (4)$$

$$\frac{OS}{OR}=\frac{X\sin\phi}{X\cos\phi}=\tan\phi=\frac{6.2}{7.6}=0.8158\quad\text{or}\quad\phi=39.2072^\circ \qquad (5)$$

From Eqs. (2) and (4), we find

$$X=\sqrt{(X\sin\phi)^2+(X\cos\phi)^2}=\sqrt{(6.2)^2+(7.6)^2}=9.8082\text{ mm}$$

Equations (3) and (5) give

$$Y=\frac{6.0}{\sin\phi}=\frac{6.0}{\sin 39.2072^\circ}=9.4918\text{ mm}$$

1.82 (a) $x(t) = \frac{A}{1000}\cos(50t + \alpha)$ m where A is in mm ---- (E_1)

$x(0) = \frac{A}{1000}\cos\alpha = 0.003$, $A\cos\alpha = 3$ ---- (E_2)

$\dot{x}(0) = -\frac{50A}{1000}\sin\alpha = 1$, $A\sin\alpha = -20$ ---- (E_3)

$$A = \{(A\cos\alpha)^2 + (A\sin\alpha)^2\}^{1/2} = 20.2237 \text{ mm}$$

$$\alpha = \tan^{-1}\left(\frac{A\sin\alpha}{A\cos\alpha}\right) = \tan^{-1}(-6.6667) = -81.4692^\circ = -1.4219 \text{ rad}$$

$$x(t) = 20.2237\cos(50t - 1.4219) \text{ mm}$$

(b) $\cos(A+B) = \cos A\cos B - \sin A\sin B$

Eq. (E_1) can be expressed as $x(t) = A\cos 50t\cdot\cos\alpha - A\sin 50t\cdot\sin\alpha$

$= A_1\cos\omega t + A_2\sin\omega t$

where $\omega = 50$, $A_1 = A\cos\alpha$, $A_2 = -A\sin\alpha$

$$\therefore\ x(t) = (3\cos 50t + 20\sin 50t) \text{ mm}$$

1.83 $x(t) = A_1\cos\omega t + A_2\sin\omega t$

$\frac{dx}{dt}(t) = -A_1\omega\sin\omega t + A_2\omega\cos\omega t$, $\frac{d^2x}{dt^2} = -A_1\omega^2\cos\omega t - A_2\omega^2\sin\omega t$

$\frac{d^2x}{dt^2} = -\omega^2 x(t)$ where ω^2 is a constant

Hence $x(t)$ is a simple harmonic motion.

1.84 (a) Using trigonometric relations:

$x_1(t) = 5(\cos 3t\cos 1 - \sin 3t\sin 1)$

$x_2(t) = 10(\cos 3t\cos 2 - \sin 3t\sin 2)$

$x(t) = x_1(t) + x_2(t) = \cos 3t(5\cos 1 + 10\cos 2) - \sin 3t(5\sin 1 + 10\sin 2)$

If $x(t) = A\cos(\omega t + \alpha) = A\cos\omega t\cos\alpha - A\sin\omega t\sin\alpha$,

$\omega = 3$, $A\cos\alpha = 5\cos 1 + 10\cos 2 = -1.4599$,

$A\sin\alpha = 5\sin 1 + 10\sin 2 = 13.3003$

$$A = \sqrt{(A\cos\alpha)^2 + (A\sin\alpha)^2} = 13.3802$$

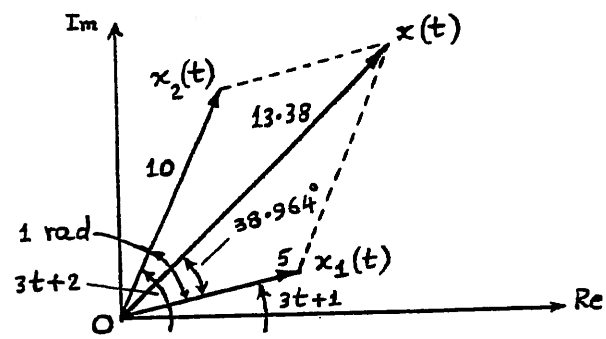
$$\alpha = \tan^{-1}\left(\frac{A\sin\alpha}{A\cos\alpha}\right) = \tan^{-1}(-9.1104) = 96.2640^\circ = 1.68 \text{ rad}$$

Angle between $x_1(t)$ and $x(t)$ is $96.2640^\circ - 57.3^\circ = 38.964^\circ$

(b) Using vector addition:

For an arbitrary value of $(\omega t + 1)$, harmonic motions $x_1(t)$ and $x_2(t)$ can be shown as in the figure. From vector addition, we find

$$x(t) \simeq 13.38\cos(\omega t + 1.68)$$



(C) Using complex numbers:

$$x_1(t) = \text{Re}\left\{A_1\, e^{i(\omega t+1)}\right\} = \text{Re}\left\{5\, e^{i(\omega t+1)}\right\}$$

$$x_2(t) = \text{Re}\left\{A_2\, e^{i(\omega t+2)}\right\} = \text{Re}\left\{10\, e^{i(\omega t+2)}\right\}$$

If $x(t) = \text{Re}\left\{A\, e^{i(\omega t+\alpha)}\right\}$,

$$A\cos(3t+\alpha) = A_1 \cos(3t+1) + A_2 \cos(3t+2)$$

i.e. $A(\cos 3t \cos\alpha - \sin 3t \sin\alpha) = 5(\cos 3t \cdot \cos 1 - \sin 3t \cdot \sin 1) + 10(\cos 3t \cdot \cos 2 - \sin 3t \cdot \sin 2)$

i.e. $A\cos\alpha = 5\cos 1 + 10\cos 2$, $A\sin\alpha = 5\sin 1 + 10\sin 2$

$A = 13.3802$, $\alpha = 1.68$ rad

$$x(t) = \text{Re}\left\{13.3802\, e^{i(3t+1.68)}\right\}$$

1.85 $x(t) = 10\sin(\omega t + 60^\circ) = x_1(t) + x_2(t)$

where $x_1(t) = 5\sin(\omega t + 30^\circ)$ and $x_2(t) = A\sin(\omega t + \alpha^\circ)$

$$10(\sin\omega t \cos 60^\circ + \cos\omega t \sin 60^\circ) = 5(\sin\omega t \cdot \cos 30^\circ + \cos\omega t \cdot \sin 30^\circ) + A(\sin\omega t \cdot \cos\alpha^\circ + \cos\omega t \cdot \sin\alpha^\circ)$$

$10\cos 60^\circ = 5\cos 30^\circ + A\cos\alpha^\circ$; $A\cos\alpha^\circ = 0.6699$

$10\sin 60^\circ = 5\sin 30^\circ + A\sin\alpha^\circ$; $A\sin\alpha^\circ = 6.1603$

$$A = \sqrt{0.6699^2 + 6.1603^2} = 6.1966$$

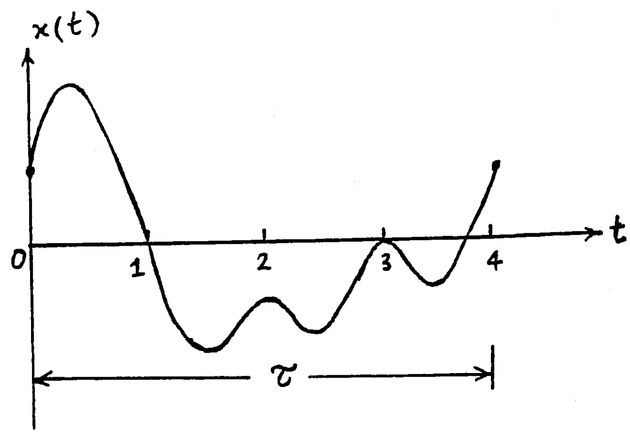
$$\alpha = \tan^{-1}(6.1603/0.6699) = 83.7938^\circ$$

$$x_2(t) = 6.1966\sin(\omega t + 83.7938^\circ)$$

1.86 $x(t) = \frac{1}{2}\cos\frac{\pi}{2}t + \sin\pi t$

$$= \frac{1}{2}\cos\frac{\pi}{2}t\left(1 + 4\sin\frac{\pi}{2}t\right)$$

From the nature of the graph of $x(t)$, it can be seen that $x(t)$ is periodic with a time period of $\tau = 4$.



1.87 If $x(t)$ is harmonic, $\ddot{x}(t) = -\omega^2 x(t)$

Here $x(t) = 2\cos 2t + \cos 3t$

$\ddot{x}(t) = -8\cos 2t - 9\cos 3t \neq -$ constant times $x(t)$

$\therefore$ $x(t)$ is not harmonic

1.88

$$x(t) = \frac{1}{2}\cos\frac{\pi}{2}t - \cos \pi t$$

$$\ddot{x}(t) = -\frac{\pi^2}{8}\cos\frac{\pi}{2}t + \pi^2 \cos \pi t \neq - \text{constant times } x(t)$$

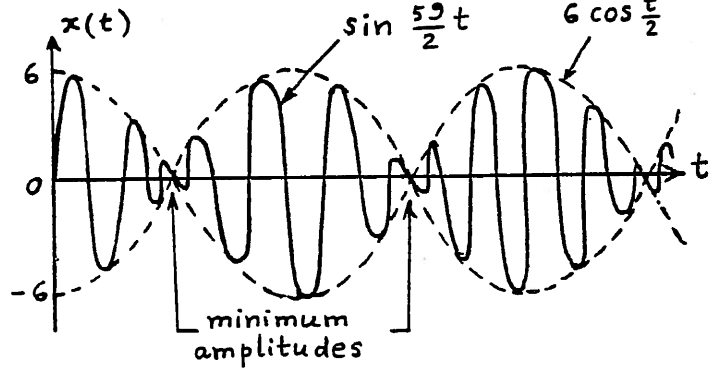
$\therefore$ $x(t)$ is not harmonic

1.89

$$x(t) = x_1(t) + x_2(t) = 3 \sin 30t + 3 \sin 29t$$

since $\sin A + \sin B = 2 \sin \frac{A+B}{2} \cos \frac{A-B}{2}$,

$$x(t) = \left(6 \cos \frac{t}{2}\right) \sin \frac{59}{2} t$$



This equation shows that the amplitude $\left(6 \cos \frac{t}{2}\right)$ varies with time between a maximum value of 6 and a minimum value of 0. The frequency of this oscillation (beat frequency) is $\omega_b = 1$.

Note: Beat frequency is twice the frequency of the term $6 \cos \frac{t}{2}$ since two peaks pass in each cycle of $\left(6 \cos \frac{t}{2}\right)$.

1.90

The resultant motion of two harmonic motions having identical amplitudes (X) but slightly different frequencies (ω and $\omega + \delta\omega$) is given by Eq. (1.67):

$$x(t) = 2\,X \cos\left(\omega\, t + \frac{\delta\omega\, t}{2}\right) \cos\left(\frac{\delta\,\omega\, t}{2}\right)$$

Thus the maximum amplitude of the resultant motion is equal to 2X and the beat frequency is equal to $\delta\omega$. From Fig. 1.113, we find that $2X \approx 5$ mm or $X = 2.5$ mm and

$$\frac{\delta\omega}{2} = \frac{2\,\pi}{\tau_{\text{beat}}} = \frac{2\,\pi}{\tau_{\text{larger}}} = \frac{2\,\pi}{2\,(12.6 - 4.2)} = 0.374 \text{ rad/sec}$$

or $\delta\omega = 0.748$ rad/sec and $\omega + \frac{\delta\,\omega}{2} = \frac{2\,\pi}{\tau_{\text{smaller}}} = \frac{2\,\pi}{1} = 6.2832$ rad/sec

Hence $\omega = 6.2832 - 0.3740 = 5.9092$ rad/sec. Thus the amplitudes of the two motions $= X = 2.5$ mm and their frequencies are $\omega = 5.9092$ rad/sec and $\omega + \delta\omega = 5.9092 + 0.7480 = 6.6572$ rad/sec.

1.91

$A = 0.05$ m, $\omega = 10$ Hz $= 62.832$ rad/sec

$$\text{period} = \tau = \frac{2\pi}{\omega} = \frac{2\pi}{62.832} = 0.1 \text{ sec}$$

$$\text{maximum velocity} = A\omega = 0.05 \times 62.832 = 3.1416 \text{ m/s}$$

$$\text{maximum acceleration} = A\omega^2 = 0.05\,(62.832)^2 = 197.393 \text{ m/s}^2$$

(1.92)
$\omega = 15$ cps $= 94.248$ rad/sec
$\ddot{x}_{max} = 0.5\,g = 0.5\,(9.81) = 4.905$ m/s^2 $= A\omega^2$
$A =$ amplitude $= 4.905/(94.248)^2 = 0.0005522$ m
$\dot{x}_{max} =$ max. velocity $= A\omega = 0.05204$ m/s

(1.93)
$x = A\cos\omega t$, $\quad x_{max} = A = 0.25$ mm, $\ddot{x} = -\omega^2 A\cos\omega t$
$\ddot{x}_{max} = A\omega^2 = 0.4\,g = 0.4\,(9.81)$ m/s^2 $= 3924$ mm/s^2
$\omega^2 = 3924/0.25 = 15696\,(\text{rad/s})^2$
$\omega = 125.2837$ rad/s $= 125.2837/2\pi$ rev/s
$= 19.9395$ rev/s $= 1196.3682$ rev/min (rpm).

1.94

$x(t) = A\, e^{-\alpha t}$

$x(1) = 0.752985 = A\, e^{-\alpha}$ (1)

$x(2) = 0.226795 = A\, e^{-\alpha t}$ (2)

Divide Eq. (1) by Eq. (2):

$$\frac{0.752985}{0.226795} = \frac{A\, e^{-t}}{A\, e^{-2t}}$$

i.e., $e^{\alpha} = 3.4965$

or $\alpha = \log_e 3.4965 = 1.2517$ (3)

From Eqs. (1) and (3), we find

$$A = \frac{0.752985}{e^{-1.2517}} = 2.6328$$ (4)

1.95

Displacement $= x(t) = 18 \cos 8t$ mm

(a) Frequency of harmonic motion $= \omega = 8$ rad/s

$$\text{Period} = \tau = \frac{2\pi}{\omega} = \frac{2\pi}{8} = 0.7854 \text{ s}$$

(b) Frequency of oscillation :

$$\omega = 8 \text{ rad/s} = \frac{8}{2\pi} \text{ Hz} = 1.2732 \text{ Hz}$$

1.96

Motion of the machine = $x = 8 \sin(5t+1)$ (1)

Using the formula for $\sin(A+B)$, Eq. (1) can be written as

$$\sin(5t+1) = \sin 5t \cdot \cos 1 + \cos 5t \cdot \sin 1 \quad (2)$$

and hence

$$x = 8 \sin 5t \cdot \cos 1 + 8 \cos 5t \cdot \sin 1 \quad (3)$$

Eq. (3) is in the form

$$x = A \sin 5t + B \cos 5t \quad (4)$$

with

$$A = 8 \cos 1 = 8 (0.5403) = 4.3224 \quad (5)$$

and

$$B = 8 \sin 1 = 8 (0.8414) = 6.7312 \quad (6)$$

1.97

$$x(t) = -3.0 \sin 5t - 2.0 \cos 5t \qquad (1)$$

Eq. (1) can be expressed in the form

$$x(t) = A \cos(5t + \phi)$$

$$= A \cos 5t \cdot \cos\phi - A \sin 5t \cdot \sin\phi \qquad (2)$$

Comparing corresponding terms of Eqs. (1) and (2), we obtain

$$A \cos\phi = -2.0 \qquad (3)$$

$$A \sin\phi = 3.0 \qquad (4)$$

Dividing Eq. (4) by Eq. (3), we find

$$\tan\phi = -1.5 \quad \text{or} \quad \phi = -56.3099^\circ \qquad (5)$$

which gives

$$\cos\phi = 0.5547 \qquad (6)$$

Equations (3) and (6) give

$$A = \frac{-2.0}{\cos\phi} = -\frac{2.0}{0.5547} = -3.6055 \qquad (7)$$

$$\therefore\ x(t) = A \cos(5t + \phi)$$

$$= -3.6055 \cos(5t - 56.3099^\circ)$$

$$= -3.6055 \cos(5t - 0.9828) \qquad (8)$$

1.98

Displacement:

$$x(t) = 0.2 \sin(5t + 3) \quad m$$

Velocity:

$$\dot{x}(t) = 1.0 \cos(5t + 3) \quad m/s$$

Acceleration:

$$\ddot{x}(t) = -5.0 \sin(5t + 3) \quad m/s^2$$

Amplitudes of displacement, velocity and acceleration are:

$$x_{max} = 0.2 \ m, \quad \dot{x}_{max} = 1.0 \ m/s, \quad \ddot{x}_{max} = 5.0 \ m/s^2$$

1.99

$$x(t) = 0.15 \sin 4t + 2.0 \cos 4t \quad \text{in} \qquad (1)$$

By expressing Eq. (1) as

$$x(t) = A \sin(4t + \phi)$$

$$= A(\sin 4t \cos \phi + \cos 4t \sin \phi)$$

we obtain

$$A \cos \phi = 0.15 \qquad (2)$$

$$A \sin \phi = 2.00 \qquad (3)$$

Eqs. (2) and (3) yield

$$\tan \phi = \frac{2.00}{0.15} = 13.3333 \quad \text{or} \quad \phi = 85.7108^\circ$$

$$= 1.4959 \text{ rad}$$

and

$$A = \frac{0.15}{\cos \phi} = \frac{0.15}{0.0748} = 2.0056$$

$$\therefore \quad x(t) = 2.0056 \sin(4t + 1.4959) \quad \text{in}$$

Velocity:

$$\dot{x}(t) = 8.0224 \cos(4t + 1.4959) \quad \text{in/sec}$$

Acceleration:

$$\ddot{x}(t) = -32.0896 \sin(4t + 1.4959) \quad \text{in/sec}^2$$

Amplitudes of displacement, velocity and acceleration are:

$$x_{max} = 2.0056 \quad \text{in}$$

$$\dot{x}_{max} = 8.0224 \quad \text{in/sec}$$

$$\ddot{x}_{max} = 32.0896 \quad \text{in/sec}^2$$

1.100

$$x(t) = 0.05 \sin(6t + \phi) \text{ m}$$

$$x(t = 0) = 0.04 = 0.05 \sin \phi$$

or $\quad \sin \phi = \dfrac{0.04}{0.05} = 0.8$

which gives

$$\phi = 53.1301^\circ \text{ or } 0.9273 \text{ rad}$$

1.101

$$x(t) = A \sin(6t + \phi) \quad m \tag{1}$$

$$\dot{x}(t) = 6A \cos(6t + \phi) \quad m/s \tag{2}$$

At $t=0$:

$$x(0) = A \sin\phi = 0.05 \ m \tag{3}$$

$$\dot{x}(0) = 6A \cos\phi = 0.005 \ m/s \tag{4}$$

Divide Eq. (3) by Eq. (4) to find

$$\frac{\tan\phi}{6} = \frac{0.05}{0.005} = 10$$

or $\quad \phi = \tan^{-1}(60) = 89.0451^\circ = 1.5541 \text{ rad} \quad (5)$

Eqs. (3) and (5) give

$$A \sin 1.5541 = 0.05$$

or $\quad A = \dfrac{0.05}{0.999861} = 0.05 \ m \quad (6)$

1.102

Frequency = 20 Hz = 20 (2π) = 40π rad/s

Amptitude of acceleration = $0.5\,g$ = $0.5\,(9.81)$

$= 4.905\ m/s^2$

If $x(t) = A \sin \omega t$,

$\dot{x}(t) = A\omega \cos \omega t$

$\ddot{x}(t) = -A\omega^2 \sin \omega t$

In the present case,

$A\omega^2 = 4.905 = A\,(40\pi)^2$

or $A = \dfrac{4.905}{(40\pi)^2} = 0.0003106\ m = 0.3106\ mm$

Hence the displacement $x(t)$, velocity $\dot{x}(t)$ and acceleration $\ddot{x}(t)$ of the machine are given by

$x(t) = A \sin \omega t = 0.3106 \sin 125.6640\,t$ mm

$\dot{x}(t) = A\omega \cos \omega t = 0.03903 \cos 125.6640\,t$ m/s

$\ddot{x}(t) = -A\omega^2 \sin \omega t = -4.9047 \sin 125.6640\,t\ m/s^2$

1.103

$x_{max} = 0.5$ mm

$\ddot{x}_{max} = 0.5g = 4.905 \; m/s^2$

If $x(t)$ is a harmonic function,

$$x(t) = A \sin \omega t$$

and

$$\ddot{x}(t) = -A\omega^2 \sin \omega t$$

For the given data,

$$A = 0.5 \text{ mm} = 0.0005 \text{ m}$$

and

$$A\omega^2 = 4.905 \quad \text{or} \quad \omega^2 = \frac{4.905}{0.0005} = 9810.0$$

Hence $\omega = 99.0454$ rad/s $= 15.7635$ Hz

$= 945.8121$ rpm

Hence the rotational speed of the rotor is:

945.8121 rpm.

1.104 $x(t) = X \sin \frac{2\pi t}{\tau}$; $x_{rms} = \left[\frac{1}{\tau} \int_0^\tau X^2 \text{ sun}^2 \frac{2\pi t}{\tau} dt \right]^{\frac{1}{2}}$

Using $\sin^2 \frac{2\pi t}{\tau} = \frac{1 - \cos \frac{4\pi t}{\tau}}{2}$, we obtain

$$x_{rms} = \left[\frac{X^2}{\tau} \int_0^\tau \left(\frac{1}{2} - \frac{1}{2} \cos \frac{4\pi t}{\tau} \right) dt \right]^{\frac{1}{2}} = \left[\frac{X^2}{\tau} \left\{ \frac{t}{2} - \frac{1}{2} \frac{\tau}{4\pi} \sin \frac{4\pi t}{\tau} \right\} \Big|_0^\tau \right]^{\frac{1}{2}}$$

$$= \left[\frac{X^2}{\tau} \left\{ \frac{\tau}{2} - \frac{\tau}{8\pi} \sin 4\pi - 0 + 0 \right\} \right]^{\frac{1}{2}} = \frac{X}{\sqrt{2}}$$

1.105 $x(t) = \frac{A t}{\tau}$; $0 \le t \le \tau$

$$x_{rms} = \left\{ \frac{1}{\tau} \int_0^\tau \frac{A^2}{\tau^2} t^2 dt \right\}^{\frac{1}{2}} = \left\{ \frac{1}{\tau} \frac{A^2}{\tau^2} \left(\frac{t^3}{3} \right) \Big|_0^\tau \right\}^{\frac{1}{2}} = \left\{ \frac{A^2}{\tau^3} \frac{\tau^3}{3} \right\}^{\frac{1}{2}} = \left(\frac{A^2}{3} \right)^{\frac{1}{2}} = \frac{A}{\sqrt{3}}$$

1.106 For even functions, $x(-t) = x(t)$.

From Eq. (1.73), $b_n = \frac{2}{\tau} \int_0^\tau x(t) \sin n\omega t \cdot dt = \frac{2}{\tau} \int_{-\tau/2}^{\tau/2} x(t) \sin n\omega t \; dt$

$$= \frac{2}{\tau} \left[\int_{-\frac{\tau}{2}}^{0} x(t) \sin n\omega t \cdot dt + \int_0^{\tau/2} x(t) \sin n\omega t \cdot dt \right] \quad \text{---- } (E_1)$$

Since $\sin(-n\omega t) = -\sin(n\omega t) =$ odd function of t, the product of $x(t)$ and $\sin n\omega t$ is an odd function.
Further, for an odd function $f(t)$, $f(-t) = -f(t)$, and

$$\int_{-a}^{a} f(t)\,dt = \int_{-a}^{0} f(t)\,dt + \int_{0}^{a} f(t)\,dt = \int_{0}^{a} f(-t)\,dt + \int_{0}^{a} f(t)\,dt$$

$$= -\int_{0}^{a} f(t)\,dt + \int_{0}^{a} f(t)\,dt = 0 \qquad \text{----}(E_2)$$

Equations (E_1) and (E_2) lead to $b_n = 0$.

Also, since $\cos n\omega t$ is an even function, we get

$$a_n = \frac{2}{\tau}\int_{-\tau/2}^{\tau/2} x(t)\cos n\omega t\,dt = \frac{4}{\tau}\int_{0}^{\tau/2} x(t)\cos n\omega t\,dt$$

For odd functions, $x(-t) = -x(t)$.

From Eq. (1.72), $a_n = \frac{2}{\tau}\int_{0}^{\tau} x(t)\cos n\omega t\,dt = \frac{2}{\tau}\int_{-\tau/2}^{\tau/2} x(t)\cos n\omega t\,dt$

Since $\cos n\omega t$ is an even function, $\cos(-n\omega t) = \cos(n\omega t)$, the product of $x(t)$ and $\cos n\omega t$ is an odd function.

Hence $a_n = 0$.

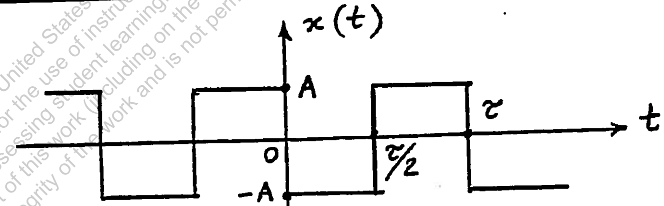
Further, since $\sin n\omega t$ is an odd function, $x(t)\sin n\omega t$ is an even function and hence

$$b_n = \frac{4}{\tau}\int_{0}^{\tau/2} x(t)\sin n\omega t\,dt$$

1.107

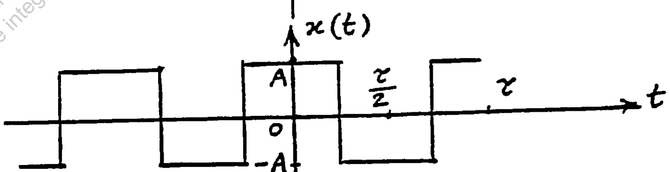
$$x(t) = \begin{cases} -A, & 0 \le t \le \frac{\tau}{2} \\ A, & \frac{\tau}{2} \le t \le \tau \end{cases}$$

(a)



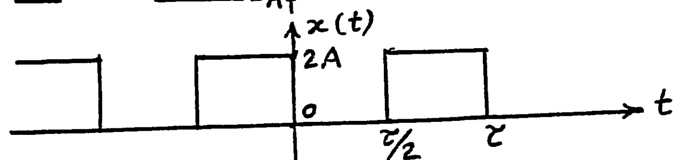
$$x(t) = \begin{cases} A, & 0 \le t \le \tau/4 \\ -A, & \frac{\tau}{4} \le t \le \frac{3\tau}{4} \\ A, & \frac{3\tau}{4} \le t \le \tau \end{cases}$$

(b)



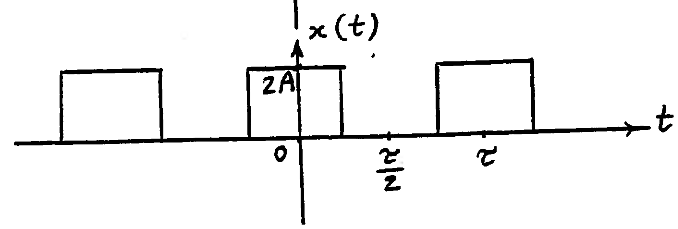
$$x(t) = \begin{cases} 0, & 0 \le t \le \tau/2 \\ 2A, & \frac{\tau}{2} \le t \le \tau \end{cases}$$

(c)



$$x(t) = \begin{cases} 2A, & 0 \le t \le \frac{\tau}{4} \\ 0, & \frac{\tau}{4} \le t \le \frac{3\tau}{4} \\ 2A, & \frac{3\tau}{4} \le t \le \tau \end{cases}$$

(d)



(a) $x(-t) = -x(t)$, odd function, hence $a_0 = a_n = 0$

$$b_n = \frac{2}{\tau}\int_0^{\tau} x(t)\sin n\omega t \cdot dt = \frac{2}{\tau}\left[-A\int_0^{\tau/2}\sin n\omega t\cdot dt + A\int_{\tau/2}^{\tau}\sin n\omega t\cdot dt\right]$$

$$= -\frac{2A}{\tau}\left(-\frac{\cos n\omega t}{n\omega}\right)_0^{\pi/\omega} + \frac{2A}{\tau}\left(-\frac{\cos n\omega t}{n\omega}\right)_{\pi/\omega}^{2\pi/\omega}$$

$$= \frac{2A}{\tau n\omega}\left(2\cos n\pi - \cos 0 - \cos 2n\pi\right)$$

$$\therefore\ x(t) = \frac{4A}{\pi}\sum_{n=1}^{\infty}\frac{1}{(2n-1)}\sin(2n-1)\omega t$$

(b) $x(-t) = x(t)$, even function, hence $b_n = 0$

$$a_0 = \frac{2}{\tau}\int_0^{\tau} x(t)\,dt = \frac{2}{\tau}\left[A\cdot(t)_0^{\tau/4} - A(t)_{\tau/4}^{3\tau/4} + A(t)_{3\tau/4}^{\tau}\right] = 0$$

$$a_n = \frac{2}{\tau}\int_0^{\tau} x(t)\cos n\omega t\cdot dt$$

$$= \frac{2A}{\tau n\omega}\left[\sin n\omega t\Big|_0^{\tau/4} - \sin n\omega t\Big|_{\tau/4}^{\frac{3\tau}{4}} + \sin n\omega t\Big|_{3\tau/4}^{\tau}\right]$$

$$= \frac{A}{n\pi}\left[2\sin\frac{n\pi}{2} - 2\sin\frac{3n\pi}{2} + \sin 2\pi n\right] = \begin{cases} 4A/n\pi & \text{for } n = 1,5,9,\ldots \\ -4A/n\pi & \text{for } n = 3,7,11,\ldots\end{cases}$$

$$\therefore\ x(t) = \frac{4A}{\pi}\sum_{n=1}^{\infty}\frac{(-1)^{n+1}}{(2n-1)}\cos\frac{2\pi(n-1)t}{\tau}$$

(c) $$a_0 = \frac{2}{\tau}\int_0^{\tau} x(t)\,dt = \frac{2}{\tau}\left[0 + 2A\ (t)\Big|_{\tau/2}^{\tau}\right] = 2A$$

$$a_n = \frac{2}{\tau}\int_0^{\tau} x(t)\cos n\omega t\,dt = \frac{4A}{n\omega\tau}\left(\sin n\omega t\right)_{\tau/2}^{\tau} = 0$$

$$b_n = \frac{2}{\tau}\int_0^{\tau} x(t)\sin n\omega t\,dt = -\frac{4A}{n\omega\tau}\left(\cos n\omega t\right)_{\tau/2}^{\tau}$$

$$= -\frac{4A}{n\omega\tau}\left(\cos 2\pi n - \cos n\pi\right)$$

$$\therefore\ x(t) = -\frac{4A}{\pi}\sum_{n=1}^{\infty}\frac{1}{(2n-1)}\sin(2n-1)\omega t \quad \text{with } \omega = 2\pi/\tau.$$

(d) $x(-t) = x(t)$, even function, hence $b_n = 0$

$$a_0 = \frac{2}{\tau}\int_0^{\tau} x(t)\,dt = \frac{2}{\tau}\left[2A\left(\frac{\tau}{4} - 0\right) + 2A\left(\tau - \frac{3\tau}{4}\right)\right] = 2A$$

$$a_n = \frac{2}{\tau}\int_0^{\tau} x(t)\cos n\omega t\,dt = \frac{4A}{n\omega\tau}\left[\left(\sin n\omega t\right)_0^{\tau/4} + \left(\sin n\omega t\right)_{\frac{3\tau}{4}}^{\tau}\right]$$

$$= \frac{4A}{n\omega\tau}\left(\sin\frac{n\pi}{2} + \sin 2n\pi - \sin\frac{3n\pi}{2}\right)$$

$$\therefore \; x(t) = \frac{4A}{\pi}\sum_{n=1}^{\infty}\frac{(-1)^{n+1}}{(2n-1)}\cos\frac{2\pi(2n-1)t}{\tau} \qquad \text{with } \omega = 2\pi/\tau.$$

1.108

$$x(t) = \begin{cases} A\sin\frac{2\pi t}{\tau} &, \; 0 \le t \le \frac{\tau}{2} \\ 0 &, \; \frac{\tau}{2} \le t \le \tau \end{cases}$$

$$a_0 = \frac{2}{\tau}\int_0^{\tau} x(t)\,dt = \frac{2A}{\tau}\int_0^{\tau/2}\sin\frac{2\pi t}{\tau}\,dt = \frac{2A}{\tau}\left(-\frac{\tau}{2\pi}\cdot\cos\frac{2\pi t}{\tau}\right)_0^{\tau/2}$$

$$= \frac{2A}{\pi}$$

$$a_n = \frac{2}{\tau}\int_0^{\tau} x(t)\cos n\omega t\,dt = \frac{2A}{\tau}\int_0^{\tau/2}\sin\frac{2\pi t}{\tau}\cdot\cos n\omega t\,.\,dt \qquad \text{----}(E_1)$$

Using the relation $\sin m\omega t\cdot\cos n\omega t = \frac{\sin(m+n)\omega t + \sin(m-n)\omega t}{2}$,

Eq. (E_1) can be rewritten as

$$a_n = \frac{A}{\tau}\int_0^{\pi/\omega}\left[\sin(1+n)\omega t + \sin(1-n)\omega t\right]dt$$

when $n = 1$, $\quad a_1 = \frac{A}{\tau}\int_0^{\pi/\omega}\sin 2\omega t\,.\,dt = 0$

when $n = 2, 3, 4, \ldots,$ $\quad a_n = \frac{A}{\tau}\left[-\frac{\cos(1+n)\omega t}{(1+n)\omega} - \frac{\cos(1-n)\omega t}{(1-n)\omega}\right]_0^{\pi/\omega}$

$$= \frac{A}{2\pi}\left[\frac{1-\cos(1+n)\pi}{1+n} + \frac{1-\cos(1-n)\pi}{1-n}\right]$$

$$= \begin{cases} 0 & \text{if } n \text{ is odd} \\ -\frac{2A}{(n-1)(n+1)\pi} & \text{if } n \text{ is even} \end{cases}$$

Similarly $\quad b_n = \frac{2}{\tau}\int_0^{\tau} x(t)\sin n\omega t\,dt = \frac{2A}{\tau}\int_0^{\tau/2}\sin\frac{2\pi t}{\tau}\cos n\omega t\,dt$

$$= \frac{A}{\tau}\int_0^{\tau/2}\left[\cos(1-n)\omega t - \cos(1+n)\omega t\right]dt$$

when $n = 1$, $\quad b_1 = \frac{A}{\tau}\int_0^{\pi/\omega}(dt - \cos 2\omega t)\,dt = \frac{A}{2}$

when $n = 2, 3, 4, \ldots,$ $\quad b_n = \frac{A}{\tau}\left[\frac{\sin(1-n)\omega t}{(1-n)\omega} - \frac{\sin(1+n)\omega t}{(1+n)\omega}\right]_0^{\pi/\omega} = 0$

$$\therefore \; x(t) = \frac{A}{\pi} + \frac{A}{2}\sin\omega t - \frac{2A}{\pi}\sum_{n=2,4,6,\ldots}^{\infty}\frac{\cos n\omega t}{(n^2-1)}$$

(1.109) $$x(t) = \begin{cases} \dfrac{2At}{\tau}, & 0 \le t \le \dfrac{\tau}{2} \\ -\dfrac{2At}{\tau} + 2A, & \dfrac{\tau}{2} \le t \le \tau \end{cases}$$

$$a_0 = \frac{2}{\tau}\int_0^{\tau} x(t)\,dt = \frac{2}{\tau}\left[\int_0^{\tau/2} \frac{2At}{\tau}\cdot dt + \int_{\tau/2}^{\tau}\left(-\frac{2At}{\tau} + 2A\right)\cdot dt\right]$$

$$= \frac{2}{\tau}\left[\frac{2A}{\tau}\cdot\frac{t^2}{2}\Big|_0^{\tau/2} - \frac{2A}{\tau}\cdot\frac{t^2}{2}\Big|_{\tau/2}^{\tau} + 2A\cdot t\Big|_{\tau/2}^{\tau}\right]$$

$$= \frac{2}{\tau}\left[\frac{A\tau}{4} - \frac{3A\tau}{4} + A\tau\right] = A$$

$$a_n = \frac{2}{\tau}\int_0^{\tau} x(t)\cos n\omega t\,dt$$

$$= \frac{2}{\tau}\left[\int_0^{\frac{\tau}{2}} \frac{2A}{\tau}t\cos n\omega t\,dt + \int_{\tau/2}^{\tau}\left(-\frac{2A}{\tau}t + 2A\right)\cos n\omega t\,dt\right]$$

$$= \frac{2}{\tau}\left[\frac{2A}{\tau}\left\{t\,\frac{\sin n\omega t}{n\omega} + \frac{\cos n\omega t}{n^2\omega^2}\right\}_0^{\tau/2} - \frac{2A}{\tau}\left\{t\,\frac{\sin n\omega t}{n\omega} + \frac{\cos n\omega t}{n^2\omega^2}\right\}_{\tau/2}^{\tau} + 2A\left(-\frac{\sin n\omega t}{n\omega}\right)_{\tau/2}^{\tau}\right]$$

As $\tau = \dfrac{2\pi}{\omega}$,

$$a_n = \frac{\omega}{\pi}\left[\frac{A\omega}{\pi n^2\omega^2}\cos n\pi - \frac{A\omega}{\pi n^2\omega^2} - \frac{A\omega}{\pi n^2\omega^2}\cos 2\pi n + \frac{A\omega}{\pi n^2\omega^2}\cos n\pi\right]$$

$$= \frac{2A}{n^2\pi^2}\left(\cos n\pi - 1\right) = \begin{cases} -\dfrac{4A}{n^2\pi^2}, & n = 1, 3, 5, \dots \\ 0, & n = 2, 4, 6, \dots \end{cases}$$

$$b_n = \frac{2}{\tau}\int_0^{\tau} x(t)\sin n\omega t\,dt = \frac{2}{\tau}\left[\int_0^{\tau/2}\frac{2A}{\tau}t\sin n\omega t\,dt + \int_{\tau/2}^{\tau}\left(-\frac{2A}{\tau}t + 2A\right)\sin n\omega t\,dt\right]$$

$$= \frac{2}{\tau}\left[\frac{2A}{\tau}\left\{-\frac{t\cos n\omega t}{n\omega} + \frac{\sin n\omega t}{n^2\omega^2}\right\}_0^{\tau/2} - \frac{2A}{\tau}\left\{-\frac{t\cos n\omega t}{n\omega} + \frac{\sin n\omega t}{n^2\omega^2}\right\}_{\tau/2}^{\tau} + 2A\left(-\frac{\cos n\omega t}{n\omega}\right)_{\tau/2}^{\tau}\right]$$

$$= \frac{\omega}{\pi}\left[-\frac{A}{n\omega}\cos n\pi + \frac{2A}{n\omega}\cos 2n\pi - \frac{A}{n\omega}\cos n\pi - \frac{2A}{n\omega}\cos 2n\pi + \frac{2A}{n\omega}\cos n\pi\right] = 0$$

$$\therefore\ x(t) = \frac{A}{2} - \frac{4A}{\pi^2} \sum_{n=1,3,5,\ldots}^{\infty} \frac{1}{n^2} \cos n\omega t$$

1.110

$$x(t) = \begin{cases} \dfrac{4At}{\tau} & , \ 0 \le t \le \dfrac{\tau}{4} \\ -\dfrac{4At}{\tau} + 2A & , \ \dfrac{\tau}{4} \le t \le \dfrac{3\tau}{4} \\ \dfrac{4At}{\tau} - 4A & , \ \dfrac{3\tau}{4} \le t \le \tau \end{cases}$$

$$a_0 = \frac{2}{\tau}\int_0^{\tau} x(t)\,dt = \frac{2}{\tau}\left[\frac{4A}{\tau}\frac{t^2}{2}\Big|_0^{\tau/4} + \left(-\frac{4A}{\tau}\frac{t^2}{2} + 2At\right)_{\tau/4}^{3\tau/4} + \left(\frac{4A}{\tau}\frac{t^2}{2} - 4At\right)_{3\tau/4}^{\tau} \right] = 0$$

$$a_n = \frac{2}{\tau}\int_0^{\tau} x(t)\cos n\omega t\,dt = \frac{2}{\tau}\left[\frac{4A}{\tau}\int_0^{\tau/4} t\cos n\omega t\cdot dt - \frac{4A}{\tau}\int_{\tau/4}^{3\tau/4} t\cos n\omega t\,dt + 2A\int_{\tau/4}^{3\tau/4}\cos n\omega t\,dt + \frac{4A}{\tau}\int_{3\tau/4}^{\tau} t\cos n\omega t\,dt - 4A\int_{3\tau/4}^{\tau}\cos n\omega t\,dt \right]$$

$$= \frac{2}{\tau}\left[\frac{4A}{\tau}\left\{ t\,\frac{\sin n\omega t}{n\omega} + \frac{\cos n\omega t}{n^2\omega^2} \right\}_0^{\tau/4} - \frac{4A}{\tau}\left\{ t\,\frac{\sin n\omega t}{n\omega} + \frac{\cos n\omega t}{n^2\omega^2} \right\}_{\tau/4}^{3\tau/4} + 2A\left(\frac{\sin n\omega t}{n\omega}\right)_{\tau/4}^{3\tau/4} + \frac{4A}{\tau}\left\{ t\,\frac{\sin n\omega t}{n\omega} + \frac{\cos n\omega t}{n^2\omega^2} \right\}_{3\tau/4}^{\tau} - 4A\left(\frac{\sin n\omega t}{n\omega}\right)_{3\tau/4}^{\tau} \right]$$

$$= \frac{\omega}{\pi}\Big[\sin\frac{n\pi}{2}\left(\frac{A}{n\omega} + \frac{A}{n\omega} - \frac{2A}{n\omega}\right) + \cos\frac{n\pi}{2}\left(\frac{2A}{\pi n^2\omega} + \frac{2A}{\pi n^2\omega}\right) + \sin\frac{3n\pi}{2}\left(-\frac{3A}{n\omega} + \frac{2A}{n\omega} - \frac{3A}{n\omega} + \frac{4A}{n\omega}\right) + \cos\frac{3n\pi}{2}\left(-\frac{2A}{\pi n^2\omega} - \frac{2A}{\pi n^2\omega}\right) + \cos 2\pi n\left(\frac{2A}{\pi n^2\omega}\right) - \cos 0\left(\frac{2A}{\pi n^2\omega}\right)\Big] = 0$$

$$b_n = \frac{2}{\tau}\int_0^{\tau} x(t)\sin n\omega t\,dt = \frac{2}{\tau}\left[\frac{4A}{\tau}\int_0^{\tau/4} t\sin n\omega t.\,dt - \frac{4A}{\tau}\int_{\tau/4}^{3\tau/4} t\sin n\omega t.\,dt + 2A\int_{\tau/4}^{3\tau/4}\sin n\omega t\cdot dt + \frac{4A}{\tau}\int_{3\tau/4}^{\tau} t\sin n\omega t\cdot dt - 4A\int_{3\tau/4}^{\tau}\sin n\omega t\cdot dt \right]$$

$$= \frac{2}{\tau}\left[\frac{4A}{\tau}\left\{ \frac{1}{n^2\omega^2}\sin n\omega t - \frac{t}{n\omega}\cos n\omega t \right\}_0^{\tau/4 = \frac{\pi}{2\omega}} - \frac{4A}{\tau}\left\{ \frac{1}{n^2\omega^2}\sin n\omega t - \frac{t}{n\omega}\cos n\omega t \right\}_{\frac{\tau}{4}=\frac{\pi}{2\omega}}^{\frac{3\tau}{4}=\frac{3\pi}{2\omega}} + 2A\left(-\frac{\cos n\omega t}{n\omega}\right)_{\frac{\tau}{4}=\frac{\pi}{2\omega}}^{\frac{3\tau}{4}=\frac{3\pi}{2\omega}} + \frac{4A}{\tau}\left\{ \frac{1}{n^2\omega^2}\sin n\omega t \right.\right.$$

$$- \frac{t}{n\omega} \cos n\omega t \Big\}_{\frac{3\tau}{4} = \frac{3\pi}{2\omega}}^{\tau = \frac{2\pi}{\omega}} - 4A \left(- \frac{\cos n\omega t}{n\omega} \right)_{\frac{3\tau}{4} = \frac{3\pi}{2\omega}}^{\tau = \frac{2\pi}{\omega}} \Bigg]$$

$$= \frac{4A}{\pi^2 n^2} \left(\sin \frac{n\pi}{2} - \sin \frac{3n\pi}{2} \right) = \begin{cases} 0 & \text{if } n \text{ is even} \\ \frac{8A}{\pi^2 n^2} (-1)^{\frac{n-1}{2}} & \text{if } n \text{ is odd} \end{cases}$$

$$\therefore\ x(t) = \frac{8A}{\pi^2} \sum_{n=1,3,5,\ldots}^{\infty} (-1)^{\frac{n-1}{2}} \frac{\sin n\omega t}{n^2}$$

1.111

$$x(t) = A\left(1 - \frac{t}{\tau}\right), \quad 0 \le t \le \tau$$

$$a_0 = \frac{2}{\tau} \int_0^{\tau} x(t)\, dt = \frac{2A}{\tau} \int_0^{\tau} \left(1 - \frac{t}{\tau}\right) dt = \frac{2A}{\tau} \left(t - \frac{t^2}{2\tau}\right)_0^{\tau} = A$$

$$a_n = \frac{2}{\tau} \int_0^{\tau} x(t) \cos n\omega t\, dt = \frac{2A}{\tau} \left(\frac{\sin n\omega t}{n\omega} - \frac{t}{\tau} \frac{\sin n\omega t}{n\omega} - \frac{\cos n\omega t}{\tau n^2 \omega^2} \right)_0^{2\pi/\omega}$$

$$= 0$$

$$b_n = \frac{2}{\tau} \int_0^{\tau} x(t) \sin n\omega t\, dt = \frac{2A}{\tau} \left(- \frac{\cos n\omega t}{n\omega} + \frac{t}{\tau} \frac{\cos n\omega t}{n\omega} - \frac{\sin n\omega t}{\tau n^2 \omega^2} \right)_0^{2\pi/\omega}$$

$$= \frac{A}{\pi n}$$

$$\therefore\ x(t) = \frac{A}{2} + \frac{A}{\pi} \sum_{n=1}^{\infty} \frac{\sin n\omega t}{n}$$

1.112

The truncated series of k terms can be denoted as

$$\bar{x}(t) = \frac{\bar{a}_0}{2} + \sum_{n=1}^{k} \bar{a}_n \cos n\,\omega\, t + \sum_{n=1}^{k} \bar{b}_n \sin n\,\omega\, t \tag{1}$$

with $\bar{x}(t)$ denoting an approximation to the exact x(t) given by Eq. (1.70). The error to be minimized is given by

$$E = \int_{-\pi/\omega}^{\pi/\omega} e^2(t)\, dt \tag{2}$$

$$\text{where} \quad e(t) = x(t) - \bar{x}(t) \tag{3}$$

and x(t) is the exact value (with infinite series on the right hand side of Eq. (1)). Treating E as a function of the unknowns $\bar{a}_n$ and $\bar{b}_n$, it can be minimized by setting:

$$\frac{\partial E}{\partial \bar{a}_n} = 2 \int_{-\pi/\omega}^{\pi/\omega} \left\{ x(t) - \bar{x}(t) \right\} \left(- \cos n\,\omega\, t \right) dt = 0 \tag{4}$$

$$\frac{\partial E}{\partial \bar{b}_n} = 2 \int_{-\pi/\omega}^{\pi/\omega} \left\{ x(t) - \bar{x}(t) \right\} \left(- \sin n\,\omega\, t \right) dt = 0 \tag{5}$$

Rearranging Eq. (4) gives

$$\int_{-\pi/\omega}^{\pi/\omega} x(t) \cos n\,\omega\, t\, dt = \int_{-\pi/\omega}^{\pi/\omega} \overline{x}(t) \cos n\,\omega\, t\, dt \tag{6}$$

Using orthogonalty property, the right hand side of Eq. (6) can be expressed as

$$\int_{-\pi/\omega}^{\pi/\omega} \overline{x}(t) \cos n\,\omega\, t\, dt = \begin{cases} 0 & \text{for } m \neq n \\ \dfrac{\overline{a}_n\, \pi}{\omega} & \text{for } m = n \end{cases} \tag{7}$$

This leads to

$$\int_{-\pi/\omega}^{\pi/\omega} x(t) \cos n\,\omega\, t\, dt = \frac{\overline{a}_n\, \pi}{\omega} \tag{8}$$

$$\text{or} \quad \overline{a}_n = \frac{\omega}{\pi} \int_{-\pi/\omega}^{\pi/\omega} x(t) \cos n\,\omega\, t\, dt \quad ; \quad n = 0, 1, 2, \ldots, k \tag{9}$$

In a similar manner, we can derive:

$$\overline{b}_n = \frac{\omega}{\pi} \int_{-\pi/\omega}^{\pi/\omega} x(t) \sin n\,\omega\, t\, dt \quad ; \quad n = 1, 2, \ldots, k \tag{10}$$

It can be observed that Eqs. (9) and (10) are simlar to those of Eqs. (E.3) and (E.4).

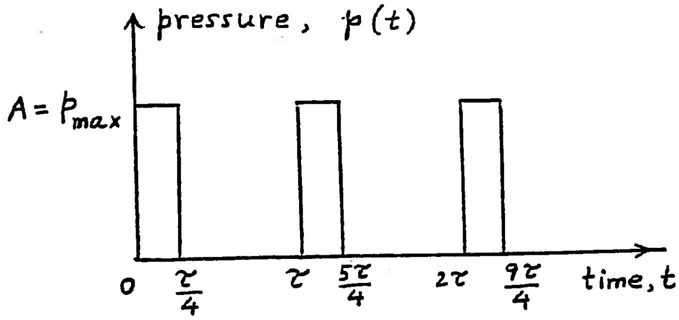
1.113

i	t_i	x_i	$n=1$: $x_i \cos \frac{2\pi t_i}{0.32}$	$n=1$: $x_i \sin \frac{2\pi t_i}{0.32}$	$n=2$: $x_i \cos \frac{4\pi t_i}{0.32}$	$n=2$: $x_i \sin \frac{4\pi t_i}{0.32}$	$n=3$: $x_i \cos \frac{6\pi t_i}{0.32}$	$n=3$: $x_i \sin \frac{6\pi t_i}{0.32}$
1	0.02	9	8.3149	3.4442	6.3639	6.3640	3.4441	8.3149
2	0.04	13	9.1924	9.1924	0.0000	13.0000	−9.1924	9.1923
3	0.06	17	6.5056	15.7060	−12.0209	12.0208	−15.7059	−6.5057
4	0.08	29	0.0000	29.0000	−29.0000	0.0000	0.0000	−29.0000
5	0.10	43	−16.4556	39.7267	−30.4053	−30.4059	39.7271	−16.4548
6	0.12	59	−41.7195	41.7191	0.0000	−59.0000	41.7187	41.7199
7	0.14	63	−58.2045	24.1087	44.5482	−44.5472	−24.1101	58.2040
8	0.16	57	−57.0000	0.0000	57.0000	0.0000	−57.0000	0.0000
9	0.18	49	−45.2700	−18.7518	34.6477	34.6487	−18.7505	−45.2705
10	0.20	35	−24.7485	−24.7489	0.0000	35.0000	24.7493	−24.7482
11	0.22	35	−13.3936	−32.3359	−24.7493	24.7482	32.3354	13.3950
12	0.24	41	0.0000	−41.0000	−41.0000	0.0000	0.0000	41.0000
13	0.26	47	17.9866	−43.4221	−33.2333	−33.2347	−43.4229	17.9847
14	0.28	41	28.9917	−28.9911	0.0000	−41.0000	−28.9905	−28.9923
15	0.30	13	12.0105	−4.9747	9.1927	−9.1921	4.9755	−12.0102
16	0.32	7	7.0000	0.0000	7.0000	0.0000	7.0000	0.0000

$\sum_{i=1}^{16}(\ )$	558	−166.7897	−31.3278	−11.6552	−91.5984	−43.2234	26.8281
$\frac{1}{8}\sum_{i=1}^{16}(\ )$	69.75	−20.8487	−3.9160	−1.4569	−11.4498	−5.4029	3.3535

1.114 Speed = 100 rpm

In a minute, a point will be subjected to the maximum pressure, $A = p_{max} = 100$ psi, $100 \times 4 = 400$ times. Hence



period $= \tau = \frac{60}{400} = 0.15$ sec.

$$p(t) = \begin{cases} A, & 0 \le t \le \tau/4 \\ 0, & \tau/4 \le t \le \tau \end{cases}$$

$$a_0 = \frac{2}{\tau}\int_0^{\tau} p(t)\, dt = \frac{2}{\tau} A \left(t\right)_0^{\tau/4} = \frac{A}{2} = 50 \text{ psi}$$

$$a_m = \frac{2}{\tau}\int_0^{\tau} p(t) \cos m\omega t\, dt = \frac{2A}{\tau}\left(\frac{\sin m\omega t}{m\omega}\right)_0^{\tau/4} = \frac{A}{\pi m} \sin \frac{m\pi}{2}$$

$$b_m = \frac{2}{\tau}\int_0^{\tau} p(t) \sin m\omega t\, dt = -\frac{2A}{\tau}\left(\frac{\cos m\omega t}{m\omega}\right)_0^{\tau/4} = -\frac{A}{\pi m}\left(\cos \frac{m\pi}{2} - 1\right)$$

Evaluation of a_m and b_m:

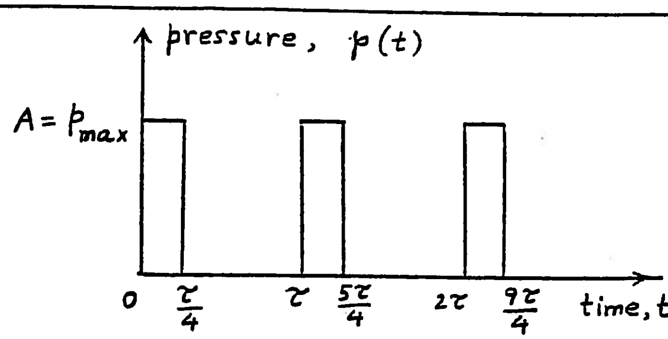
$m = 1$	$m = 2$	$m = 3$
$a_1 = \frac{A}{\pi} \sin \frac{\pi}{2} = \frac{A}{\pi} = 31.8309$ psi	$a_2 = \frac{A}{2\pi} \sin \pi = 0$	$a_3 = \frac{A}{3\pi} \sin \frac{3\pi}{2} = -10.6103$ psi
$b_1 = -\frac{A}{\pi}\left(\cos \frac{\pi}{2} - 1\right) = 31.8309$ psi	$b_2 = -\frac{A}{2\pi}\left(\cos \pi - 1\right) = 31.8309$ psi	$b_3 = -\frac{A}{3\pi}\left(\cos \frac{3\pi}{2} - 1\right) = 10.6103$ psi

$$\therefore\ p(t) = \frac{a_0}{2} + \sum_{m=1}^{\infty}\left(a_m \cos m\omega t + b_m \sin m\omega t\right) \text{ psi}$$

1.115 Speed = 200 rpm

In a minute, a point will be subjected to the maximum pressure, $A = p_{max} = 100$ psi, $200 \times 6 = 1200$ times. Hence

period $= \tau = \frac{60}{1200} = 0.05$ sec.



$$p(t) = \begin{cases} A, & 0 \le t \le \tau/4 \\ 0, & \tau/4 \le t \le \tau \end{cases}$$

$$a_0 = \frac{2}{\tau}\int_0^\tau p(t)\,dt = \frac{2}{\tau} A \left(t\right)_0^{\tau/4} = \frac{A}{2} = 50 \text{ psi}$$

$$a_m = \frac{2}{\tau}\int_0^\tau p(t)\cos m\omega t\,dt = \frac{2A}{\tau}\left(\frac{\sin m\omega t}{m\omega}\right)_0^{\tau/4} = \frac{A}{\pi m}\sin\frac{m\pi}{2}$$

$$b_m = \frac{2}{\tau}\int_0^\tau p(t)\sin m\omega t\,dt = -\frac{2A}{\tau}\left(\frac{\cos m\omega t}{m\omega}\right)_0^{\tau/4} = -\frac{A}{\pi m}\left(\cos\frac{m\pi}{2} - 1\right)$$

Evaluation of a_m and b_m:

$m = 1$	$m = 2$	$m = 3$
$a_1 = \frac{A}{\pi}\sin\frac{\pi}{2} = \frac{A}{\pi}$ $= 31.8309$ psi	$a_2 = \frac{A}{2\pi}\sin\pi = 0$	$a_3 = \frac{A}{3\pi}\sin\frac{3\pi}{2}$ $= -10.6103$ psi
$b_1 = -\frac{A}{\pi}\left(\cos\frac{\pi}{2} - 1\right)$ $= 31.8309$ psi	$b_2 = -\frac{A}{2\pi}\left(\cos\pi - 1\right)$ $= 31.8309$ psi	$b_3 = -\frac{A}{3\pi}\left(\cos\frac{3\pi}{2} - 1\right)$ $= 10.6103$ psi

$$\therefore\ p(t) = \frac{a_0}{2} + \sum_{m=1}^{\infty}\left(a_m\cos m\omega t + b_m \sin m\omega t\right) \text{ psi}$$

1.116

i	t_i	M_{t_i}	$n=1$: $M_{t_i}\cos\frac{2\pi t_i}{0.012}$	$n=1$: $M_{t_i}\sin\frac{2\pi t_i}{0.012}$	$n=2$: $M_{t_i}\cos\frac{4\pi t_i}{0.012}$	$n=2$: $M_{t_i}\sin\frac{4\pi t_i}{0.012}$	$n=3$: $M_{t_i}\cos\frac{6\pi t_i}{0.012}$	$n=3$: $M_{t_i}\sin\frac{6\pi t_i}{0.012}$
1	0.0005	770	743.7627	199.2912	666.8391	385.0010	544.4712	544.4731
2	0.0010	810	701.4802	405.0007	404.9988	701.4812	0.0000	810.0000
3	0.0015	850	601.0398	601.0417	0.0000	850.0000	−601.0442	601.0373
4	0.0020	910	454.9978	788.0845	−455.0041	788.0808	−910.0000	0.0000

i	t_i	x_i						
5	0.0025	1010	261.4043	975.5859	-874.689	504.995	-714.171	-714.184
6	0.0030	1170	0.0000	1170.0000	-1170.000	0.000	0.000	-1170.000
7	0.0035	1370	-354.5874	1323.3169	-1186.449	-685.010	968.748	-968.725
8	0.0040	1610	-805.0073	1394.2966	-804.987	-1394.309	1610.000	0.000
9	0.0045	1890	-1336.4407	1336.4229	0.000	-1890.000	1336.410	1336.454
10	0.0050	1750	-1515.5491	874.7922	875.019	-1515.534	0.000	1750.000
11	0.0055	1630	-1574.4619	421.8647	1411.634	-814.979	-1152.608	1152.560
12	0.0060	1510	-1510.0000	0.0000	1510.000	0.000	-1510.000	0.000
13	0.0065	1390	-1342.6345	-359.7671	1203.767	695.014	-982.858	-982.898
14	0.0070	1290	-1117.1677	-645.0088	644.982	1117.183	0.000	-1290.000
15	0.0075	1190	-841.4492	-841.4648	0.000	1190.000	841.479	-841.435
16	0.0080	1110	-554.9897	-961.2942	-555.021	961.276	1110.000	0.000
17	0.0085	1050	-271.7498	-1014.2249	-909.337	524.982	742.440	742.485
18	0.0090	990	0.0000	-990.0000	-990.000	0.000	0.000	990.000
19	0.0095	930	240.7123	-898.3081	-805.393	-465.018	-657.633	657.586
20	0.0100	890	445.0095	-770.7571	-444.981	-770.773	-890.000	0.000
21	0.0105	850	601.0478	-601.0337	0.000	-850.000	-601.022	-601.060
22	0.0110	810	701.4868	-404.9895	405.022	-701.468	0.000	-810.000
23	0.0115	770	743.7659	-199.2798	666.851	-384.980	544.500	-544.444
24	0.0120	750	750.0000	0.0000	750.000	0.000	750.000	0.000
$\sum_{i=1}^{24}(\;)$		27,300	-4,979.3242	1,803.7673	343.270	-1,754.047	428.734	661.855
$\frac{1}{12}\sum_{i=1}^{24}$		2,275	-414.9436	150.3139	28.606	-146.171	35.728	55.155

1.117

i	t_i	x_i	$n=1$		$n=2$		$n=3$	
			$x_i \cos \frac{2\pi t_i}{0.6}$	$x_i \sin \frac{2\pi t_i}{0.6}$	$x_i \cos \frac{4\pi t_i}{0.6}$	$x_i \sin \frac{4\pi t_i}{0.6}$	$x_i \cos \frac{6\pi t_i}{0.6}$	$x_i \sin \frac{6\pi t_i}{0.6}$
1	0.025	9.00	8.69	2.33	7.79	4.50	6.36	6.36
2	0.050	17.00	14.72	8.50	8.50	14.72	0.00	17.00
3	0.075	23.00	16.26	16.26	0.00	23.00	-16.26	16.26
4	0.100	25.00	12.50	21.65	-12.50	21.65	-25.00	0.00
5	0.125	26.00	6.73	25.11	-22.52	13.00	-18.38	-18.38
6	0.150	28.00	0.00	28.00	-28.00	0.00	0.00	-28.00
7	0.175	33.00	-8.54	31.88	-28.58	-16.50	23.33	-23.33
8	0.200	35.00	-17.50	30.31	-17.50	-30.31	35.00	0.00
9	0.225	34.00	-24.04	24.04	0.00	-34.00	24.04	24.04
10	0.250	29.00	-25.11	14.50	14.50	-25.11	0.00	29.00
11	0. 75	24.00	-23.18	6.21	20.78	-12.00	-16.97	16.97
12	0.300	26.00	-26.00	0.00	26.00	0.00	-26.00	0.00
13	0.325	32.00	-30.91	-8.28	27.71	16.00	-22.63	-22.63
14	0.350	40.00	-34.64	-20.00	20.00	34.64	0.00	-40.00
15	0.375	18.00	-12.73	-12.73	0.00	18.00	12.73	-12.73
16	0.400	8.00	-4.00	-6.93	-4.00	6.93	8.00	0.00
17	0.425	-5.00	1.29	4.83	4.33	-2.50	-3.54	-3.54
18	0.450	-14.00	0.00	14.00	14.00	0.00	0.00	-14.00
19	0.475	-28.00	-7.25	27.05	24.25	14.00	19.80	-19.80
20	0.500	-37.00	-18.50	32.04	18.50	32.04	37.00	0.00
21	0.525	-33.00	-23.33	23.33	0.00	33.00	23.33	23.34
22	0.550	-29.00	-25.11	14.50	-14.50	25.11	0.00	29.00

23	0.575	-22.00	-21.25	5.69	-19.05	11.00	-15.56	15.56
24	0.600	0.00	0.00	0.00	0.00	0.00	0.00	0.00
$\sum_{i=1}^{24}(\ )$		239.00	-241.90	282.30	39.72	147.18	45.26	-4.88
$\frac{1}{12}\sum_{i=1}^{24}(\ )$		19.92	-20.16	23.53	3.31	12.26	3.77	-0.41

1.118

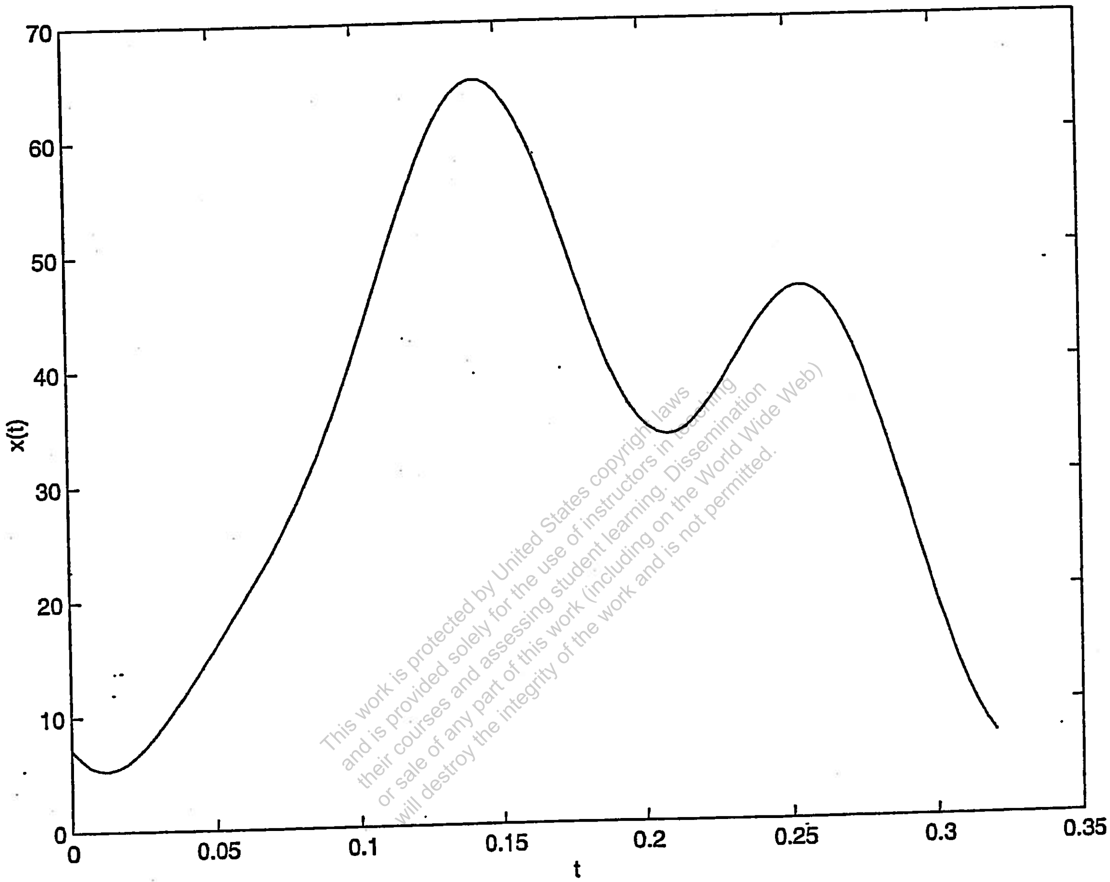
```
%=====================================================================
%
%Program1.m
%Program for calling the subroutine FORIER
%
%=====================================================================
%Run "Program1.m" in MATLAB Command Window. Program1.m and forier.m should be
%in the same file folder, and set the path to this folder
%Following 6 lines contain problem-dependent data
n=16;
m=3;
time=0.32;
x=[9 13 17 29 43 59 63 57 49 35 35 41 47 41 13 7];
t=0.02:0.02:0.32;
%end of problem-dependent data
%Following line calls subroutine forier.m
[azero,a,b,xsin,xcos]=forier(n,m,time,x,t);
%following outputs data
fprintf('Fourier series expansion of the function x(t)\n\n');
fprintf('Data:\n\n');
fprintf('Number of data points in one cycle = %3.0f \n',n);
fprintf(' \n');
fprintf('Number of Fourier Coefficients required = %3.0f \n',m);
fprintf(' \n');
fprintf('Time period = %8.6e \n\n',time);
fprintf('Station i   ')
fprintf('Time at station i: t(i)         ')
fprintf('x(i) at t(i)')
for i=1:n
   fprintf('\n %8d%25.6e%27.6e ',i,t(i),x(i));
end
fprintf(' \n\n');
fprintf('Results of Fourier analysis:\n\n');
fprintf('azero=%8.6e \n\n',azero);
fprintf('values of i       a(i)                 b(i)\n');
for i=1:m
   fprintf('%10.0g   %8.6e%20.6e \n',i,a(i),b(i));
end
```

```
%=======================================================================
%
%Subroutine forier.m
%
%=======================================================================
function [azero,a,b,xsin,xcos]=forier(n,m,time,x,t)
pi=3.1416;
sumz=0.0;
for i=1:n
   sumz=sumz+x(i);
end
azero=2.0*sumz/n;
for ii=1:m
   sums=0.0;
   sumc=0.0;
   for i=1:n
      theta=2.0*pi*t(i)*ii/time;
      xcos(i)=x(i)*cos(theta);
      xsin(i)=x(i)*sin(theta);
      sums=sums+xsin(i);
      sumc=sumc+xcos(i);
   end
   a(ii)=2.0*sumc/n;
   b(ii)=2.0*sums/n;
end
```

```
>> program1
Fourier series expansion of the function x(t)

Data:

Number of data points in one cycle =  16

Number of Fourier Coefficients required =   3

Time period = 3.200000e-001

Station i       Time at station i: t(i)         x(i) at t(i)
        1            2.000000e-002             9.000000e+000
        2            4.000000e-002             1.300000e+001
        3            6.000000e-002             1.700000e+001
        4            8.000000e-002             2.900000e+001
        5            1.000000e-001             4.300000e+001
        6            1.200000e-001             5.900000e+001
        7            1.400000e-001             6.300000e+001
        8            1.600000e-001             5.700000e+001
        9            1.800000e-001             4.900000e+001
       10            2.000000e-001             3.500000e+001
       11            2.200000e-001             3.500000e+001
       12            2.400000e-001             4.100000e+001
       13            2.600000e-001             4.700000e+001
       14            2.800000e-001             4.100000e+001
       15            3.000000e-001             1.300000e+001
       16            3.200000e-001             7.000000e+000

Results of Fourier analysis:

azero=6.975000e+001

values of i        a(i)                b(i)
        1   -2.084870e+001      -3.915985e+000
        2   -1.456887e+000      -1.144979e+001
        3   -5.402900e+000       3.353473e+000
```

1.119

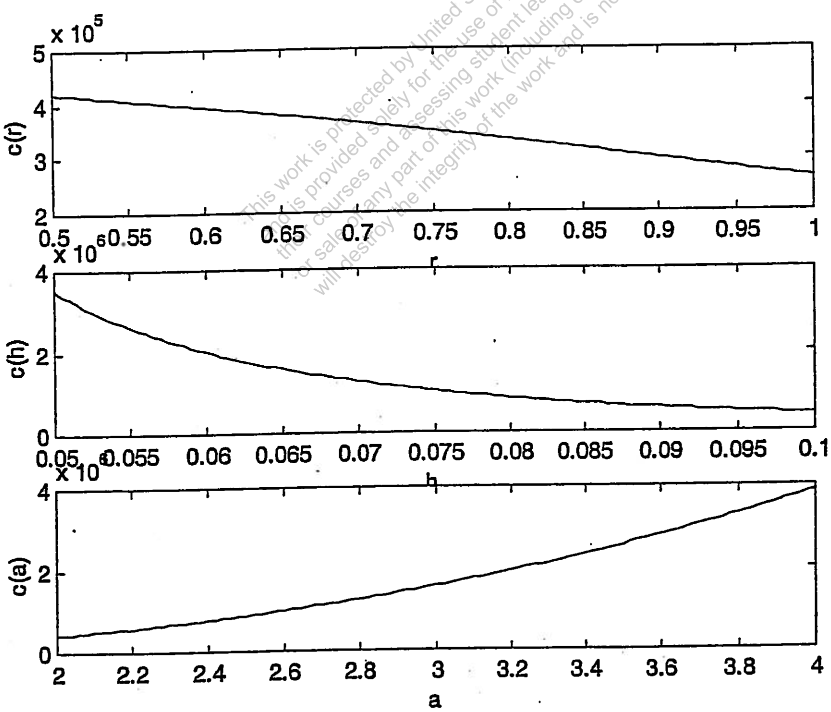
```
% Ex1_119.m
for i = 1: 101
    t(i) = 0.32*(i-1)/100;
    x(i) = 34.875 - 20.8487*cos(19.635*t(i)) - 3.9160*sin(19.635*t(i))...
        - 1.4569*cos(39.27*t(i)) - 11.4498*sin(39.27*t(i))...
        - 5.4029*cos(58.905*t(i)) + 3.3535*sin(58.905*t(i));
end
plot(t,x)
xlabel('t');
ylabel('x(t)');
```



1.120

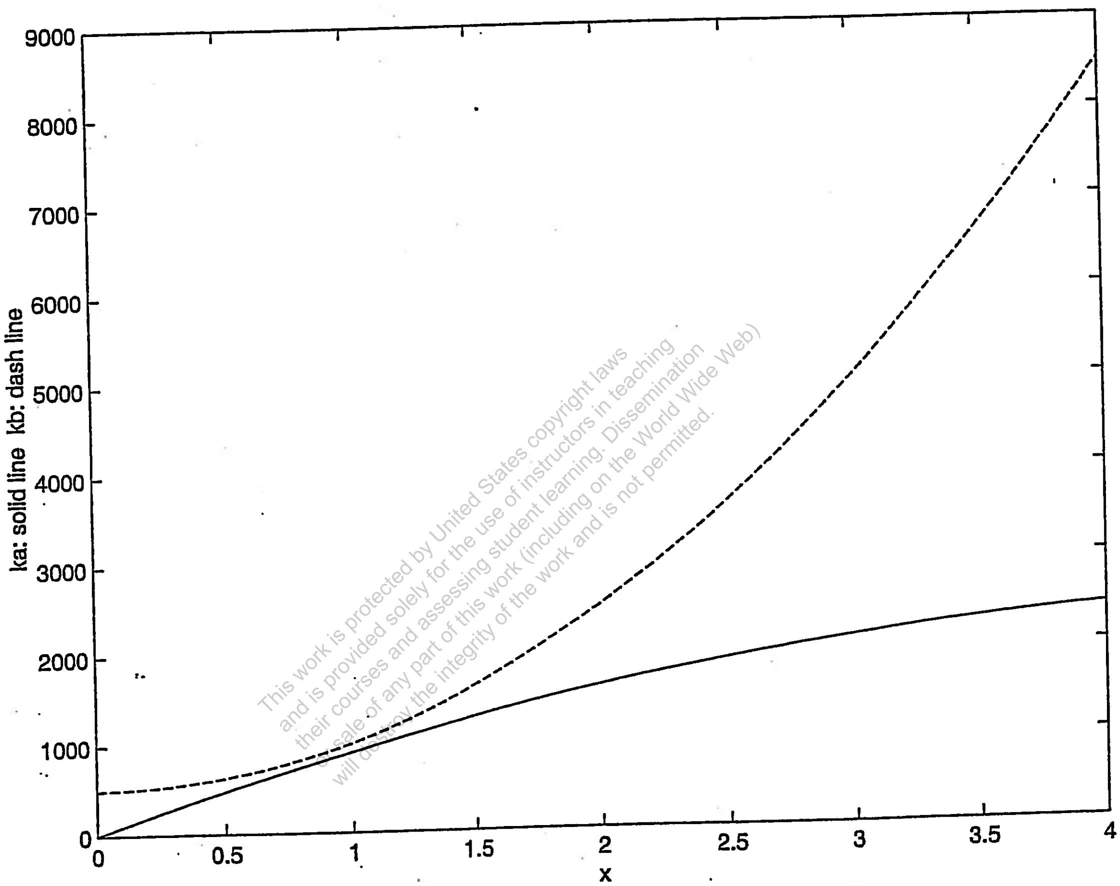
```
% Ex1_1.120.m
u = 0.3445;
l = 10;
h0 = 0.1;
a0 = 2;
r0 = 0.5;
% First case, r changes
for i = 1:101
    r(i) = 0.5 + (i-1)*0.5/100;
    c1(i) = ( 6*pi*u*l/(h0^3) ) * ( (a0 - h0/2)^2 - r(i)^2 )...
        * ( (a0^2-r(i)^2)/(a0-h0/2) - h0 );
end
```

```
% Second case, h changes
for i = 1:101
    h(i) = 0.05 + (i-1)*0.05/100;
    c2(i) = ( 6*pi*u*l/(h(i)^3) ) * ( (a0 - h(i)/2)^2 - r0^2 )...
        * ( (a0^2-r0^2)/(a0-h(i)/2) - h(i) );
end
% Third case, a changes
for i = 1:101
    a(i) = 2 + (i-1)*2/100;
    c3(i) = ( 6*pi*u*l/(h0^3) ) * ( (a(i) - h0/2)^2 - r0^2 )...
        * ( (a(i)^2-r0^2)/(a(i)-h0/2) - h0 );
end
subplot(311);
plot(r,c1);
xlabel('r');
ylabel('c(r)');
subplot(312);
plot(h,c2);
xlabel('h');
ylabel('c(h)');
subplot(313);
plot(a,c3);
xlabel('a');
ylabel('c(a)');
```



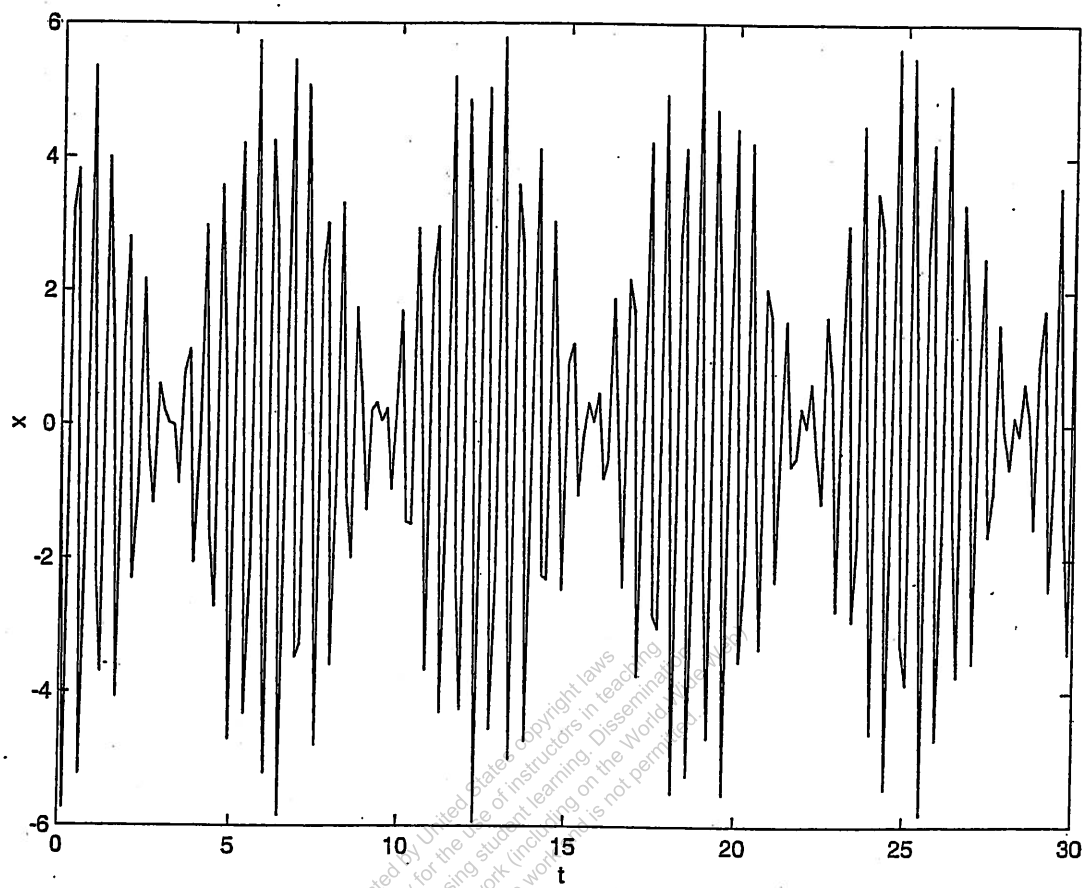
1.121

```
% Ex1_121.m
for i = 1:101
    x(i) = (i-1)*4/100;
    ka(i) = 1000*x(i) - 100*x(i)^2;
    kb(i) = 500 + 500 *x(i)^2;
end
plot(x,ka);
hold on
plot(x,kb, '--');
xlabel('x');
ylabel('ka: solid line  kb: dash line');
```



1.122

```
% Ex1_122.m
for i = 1:201
    t(i) = (i-1)*30/200;
    x1(i) = 3*sin(30*t(i));
    x2(i) = 3*sin(29*t(i));
    x(i) = x1(i) + x2(i);
end
plot(t,x);
xlabel('t');
ylabel('x');
```



6
4
2
x 0
-2
-4
-6
0
5
10
15
20
25
30
t

1.123 $x_p = r + l - r\cos\theta - l\cos\phi = r + l - r\cos\omega t - l\sqrt{1-\sin^2\phi}$ (E1)

But $l\sin\phi = r\sin\theta$, $\cos\phi = \left(1 - \frac{r^2}{l^2}\sin^2\omega t\right)^{\frac{1}{2}}$ (E2)

Using (E2) in (E1), $x_p = r + l - r\cos\omega t - l\left(1 - \frac{r^2}{l^2}\sin^2\omega t\right)^{\frac{1}{2}}$ (E3)

Let $\frac{r}{l}$ = small $\left(< \frac{1}{4}\right)$. Using $\sqrt{1-\epsilon} \approx 1 - \frac{1}{2}\epsilon$, (E3) becomes

$$x_p \approx r\left(1 + \frac{r}{2l}\right) - r\left(\cos\omega t + \frac{r}{4l}\cos 2\omega t\right) \quad \text{(E4)}$$

(a) Eq. (E4) gives $y_p = x_p - r\left(1 + \frac{r}{2l}\right) \simeq -r\left(\cos\omega t + \frac{1}{4}\frac{r}{l}\cos 2\omega t\right)$ --- (E5)

If $\frac{r}{l}$ is very small, $y_p \simeq -r\cos\omega t \Rightarrow$ harmonic motion.

(b) To have amplitude of second harmonic smaller than that of first harmonic in Eq. (E5), we need to have

$$\frac{1}{4}\frac{r}{l} \le \frac{1}{25}, \quad \text{i.e.,} \quad \frac{r}{l} \le \frac{4}{25}, \quad \text{i.e.,} \quad \frac{l}{r} \ge 6.25$$

Once the amplitude of second harmonic is smaller by a factor of 25, the amplitudes of higher harmonics arising from the expansion of square-root-term in (E3) are expected to be still smaller.

1.124 Unbalanced force developed $= P = 2\,m\,\omega^2\,r\cos\omega t$, range of force $= 0$ - 100 N, range of frequency $= 25$ - 50 Hz $= 157.08$ - 314.16 rad/sec.
Parameters to be determined: m, r, ω.
Let $r = 0.1$ m. To generate 100 N force at 25 Hz, set:

$$P_{max} = 100 = 2\,m\,(157.08)^2\,(0.1)$$

which gives

$$m = \frac{100}{2\,(157.08)^2\,(0.1)} = 0.0202641 \text{ kg} = 20.2641 \text{ g}$$

To generate 100 N force at 50 Hz, set:

$$P_{max} = 100 = 2\,m\,(314.16)^2\,(0.1)$$

which yields

$$m = \frac{100}{2\,(314.16)^2\,(0.1)} = 0.0050660 \text{ kg} = 5.0660 \text{ g}$$

1.125 Goal: Weight to be maintained at 10 ± 0.1 lb/min
Parameters to be determined: Angular velocity of crank (ω), lengths of crank and connecting rod, dimensions of the wedge, dimensions of the orifice in the hopper, dimensions of the actuating rod, and dimensions of the lever arrangement.
Given: Density of the material in the hopper.
Procedure:
Select ω based on available motor. Determine the dimensions of the orifice in the hopper which delivers approximately 10 lb/min (assuming continuous flow of material). For trial dimensions of the wedge, determine the increase/decrease in the size (diameter) of the orifice. Choose the final dimensions of the wedge such that the material flow rate delivered by the orifice lies within the specified range.

1.126 Force to be applied $= 200$ lb, frequency $= 50$ Hz $= 314.16$ rad/sec.

Procedure:

1. Select a motor that provides, either directly or through a gear system, the desired frequency. Assume that it is connected to the cam.
2. Determine the sizes and dimensions of the plate cam and the roller.
3. Choose the dimensions of the follower.
4. Select the weight as 200 lb. From the geometry, determine the range of displacement (vertical motion) of the weight.
5. Determine the force exerted due to the falling weight.

1.127 Considerations to be taken in the design of vibratory bowl feeders:

1. Suitable design of the electromagnet and its coil.
2. Radius of the bowl and the pitch of the spiral (helical) delivery track.
3. Tooling to be fixed along the spiral track to reject the defective or out-of-tolerance or incorrectly oriented parts.
4. Design of elastic supports.
5. Size and location of the outlet.

1.128 Axial spring constant of each tube $= k = \frac{A\,E}{\ell}$.

Let diameter of each tube be 0.01 m (1 cm) with thickness 0.001 m (1 mm). Then

$$A = \frac{\pi}{4}\,(D^2 - d^2) = \frac{\pi}{4}\,(0.01^2 - 0.008^2) = 28.27\ (10^{-6})\ m^2$$

This gives

$$k = \frac{(28.27\ (10^{-6}))\ (2.07\ (10^{11}))}{2} = 29.26\ (10^5)\ N/m$$

Since 76 tubes are in parallel, we have the total axial stiffness as:

$$k_{eq} = 76\ k = (76)\ (29.26\ (10^5)) = 222.38\ (10^6)\ N/m$$

The polar area moment of inertia of each tube is

$$J = \frac{\pi}{32}\,(D^4 - d^4) = \frac{\pi}{32}\,(0.01^4 - 0.008^4) = 580\ (10^{-8})\ m^4$$

Torsional stiffness of each tube is given by

$$\frac{G\,J}{\ell} = \frac{(79.6154\ (10^9))\ (580\ (10^{-8}))}{2} = 231\ (10^3)\ N\text{–}m/rad$$

For 76 tubes in parallel, equivalent torsional stiffness will be:

$$k_{t_{eq}} = (76)\ (231\ (10^3)) = 17.56\ (10^6)\ N\text{–}m/rad$$
