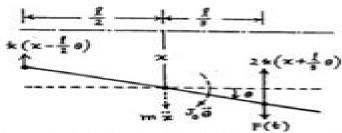
OF

$$\begin{bmatrix} m & 0 \\ 0 & J_0 \end{bmatrix} \begin{bmatrix} \ddot{x} \\ \ddot{\theta} \end{bmatrix} + \begin{bmatrix} 3 & k & k \ell/6 \\ k \ell/6 & 17 & k \ell^2/36 \end{bmatrix} \begin{bmatrix} x \\ \theta \end{bmatrix} - \begin{bmatrix} F(t) \\ \ell & F(t)/3 \end{bmatrix}$$

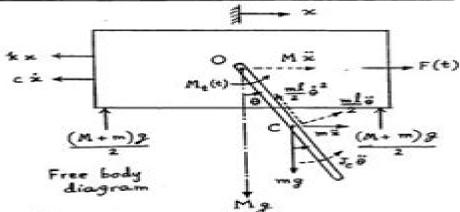
where $J_0 = \frac{m \ell^2}{12}$ and $F(t) = F_0 \sin \omega t$.

(b)

Elastic or static coupling.



(5.42)



Equations of motion with coordinates x(t) and $\theta(t)$:

For motion along x:

$$M\ddot{x} = -kx - c\dot{x} - (m\ell/2)\ddot{\theta}\cos\theta - m\ddot{x} + (m\ell/2)\dot{\theta}^{2}\sin\theta + F(t)$$
(1)

For rotation about O:

$$J_{c}\ddot{\theta} + (m\ell/2)\ddot{\theta}(\ell/2) + m\ddot{x}(\ell\cos\theta/2) = -mg(\ell/2)\sin\theta + M_{t}(t)$$
 (2)

Using $J_c = \frac{1}{12}$ m ℓ^2 , $\cos \theta \approx 1$ and $\sin \theta \approx \theta$ and neglecting the nonlinear term involving $\dot{\theta}^2$ in Eq. (1), Eqs. (1) and (2) can be rewritten in matrix form as:

$$\begin{bmatrix} (M+m) & m \, \ell/2 \\ m \, \ell/2 & (J_c+m \, \ell^2/4) \end{bmatrix} \begin{bmatrix} \ddot{x} \\ \ddot{\theta} \end{bmatrix} + \begin{bmatrix} c & 0 \\ 0 & 0 \end{bmatrix} \begin{bmatrix} \dot{x} \\ \dot{\theta} \end{bmatrix} + \begin{bmatrix} k & 0 \\ 0 & m \, g \, \ell/2 \end{bmatrix} \begin{bmatrix} x \\ \theta \end{bmatrix} = \begin{bmatrix} F(t) \\ M_t(t) \end{bmatrix}$$

Mechanical Vibrations Rao 4th Solution Manual

Scott C. Dulebohn

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