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Solutions to Chapter 2 Exercise Problems

Introduction

The solutions in this chapter have been developed using SolidWorks. Other parametric design programs will follow the same procedures although the command structure will vary from program to program. The SolidWorks files for the individual figures are available in a separate folder. Typically, the final figure gives the solution to the problem.

Problem 2.1

A slider crank mechanism is to move the slider 1" for 40° of rotation of the crank as shown in the figure. Using GCP methods, develop a graphical solution to determine the necessary crank and coupler lengths. Explicitly identify the layer structure used, and make a separate layer for all possible input dimensions. Also, explicitly list the driving and driven variables. Show the use of your graphical program to resolve the problem when the slider distance is 1.5 in and the crank rotates through an angle of 60°

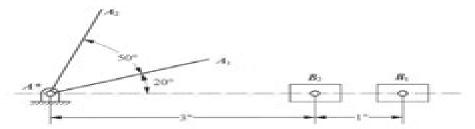


Figure P2-1.1 Original drawing for Problem 2.1.

Solution to Problem 2.1

If the fixed pivot and slider line lie on a horizontal line, the problem is defined by a total 6 variables, four of which are independent. We can represent these as shown in Table P2-1.1.

To begin the solution procedure, open the blank drawing sheet (Blank Worksheet SLDWRK) in SolidWorks. Set up the following layers: ProblemDrawing, InputVariables, SolutionConstruction, SolutionDimensions, FinalLinkage, and Dimensions. InputVariables contains only the input dimensions which will be used as input variables for the graphical program we will develop. SolutionDimensions contains only the dimensions for the two link lengths which were not specified. Dimensions contains miscellaneous dimensions such as those associated with pin

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M Lipman

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Theory of Machines and Mechanisms Joseph E. Shigley, John J. Uicker, 1994-12 The second edition of Shigley Uicker maintains the tradition of being very complete thorough and somewhat theoretical The principal changes include an expansion and updating of the dynamics material expansion of the chapter on gears an expansion of the material on mechanisms a new introductory chapter Intended for the Kinematics and Dynamics course in Mechanical Engineering Kinematics, Dynamics, and Design of Machinery Kenneth J. Waldron, Gary L. Kinzel, Sunil K. Agrawal, 2016-05-10 Kinematics Dynamics and Design of Machinery Third Edition presents a fresh approach to kinematic design and analysis and is an ideal textbook for senior undergraduates and graduates in mechanical automotive and production engineering Presents the traditional approach to the design and analysis of kinematic problems and shows how GCP can be used to solve the same problems more simply Provides a new and simpler approach to cam design Includes an increased number of exercise problems Accompanied by a website hosting a solutions manual teaching slides and MATLAB Solution Manual for Mechanics and Control of Robots Krishna C. Gupta, 1997-04-24 Intended as an programs introduction to robot mechanics for students of mechanical industrial electrical and bio mechanical engineering this graduate text presents a wide range of approaches and topics It avoids formalism and proofs but nonetheless discusses advanced concepts and contemporary applications It will thus also be of interest to practicing engineers. The book begins with kinematics emphasizing an approach based on rigid body displacements instead of coordinate transformations it then turns to inverse kinematic analysis presenting the widely used Pieper Roth and zero reference position methods. This is followed by a discussion of workplace characterization and determination One focus of the discussion is the motion made possible by sperical and other novel wrist designs The text concludes with a brief discussion of dynamics and control An extensive bibliography provides access to the current literature Kinematics and Dynamics of Planar Machinery Burton Paul, 1979

Balancing of Linkages and Robot Manipulators Vigen Arakelian, Sébastien Briot, 2015-01-27 In this book advanced balancing methods for planar and spatial linkages hand operated and automatic robot manipulators are presented It is organized into three main parts and eight chapters The main parts are the introduction to balancing the balancing of linkages and the balancing of robot manipulators The review of state of the art literature including more than 500 references discloses particularities of shaking force moment balancing and gravity compensation methods Then new methods for balancing of linkages are considered Methods provided in the second part of the book deal with the partial and complete shaking force moment balancing of various linkages A new field for balancing methods applications is the design of mechanical systems for fast manipulation Special attention is given to the shaking force moment balancing of robot manipulators Gravity balancing methods are also discussed The suggested balancing methods are illustrated by numerous examples

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