

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.SLDWRC*) 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

Kinematics Dynamics Of Machinery 3rd Edition Solution

Anthony S. Fauci



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Kinematics and Dynamics of Mechanical Systems, Second Edition Kevin Russell, Qiong Shen, Rajpal S. Sodhi, 2018-09-21 Kinematics and Dynamics of Mechanical Systems Implementation in MATLAB and SimMechanics Second Edition combines the fundamentals of mechanism kinematics synthesis statics and dynamics with real world applications and offers step by step instruction on the kinematic static and dynamic analyses and synthesis of equation systems Written for students with no knowledge of MATLAB and SimMechanics the text provides understanding of static and dynamic mechanism analysis and moves beyond conventional kinematic concepts factoring in adaptive programming 2D and 3D visualization and simulation and equips readers with the ability to analyze and design mechanical systems

Solutions of the Examples in Charles Smith's Elementary Algebra Alfred George Cracknell, Charles Smith, 1891

Multibody Systems Christoph Woernle, 2024-07-23 The book Multibody Systems guides the reader from the fundamentals of engineering mechanics to the formulations of the kinematic and dynamic equations of systems of rigid bodies suitable for computational generation Multibody systems are used for the numerical simulation of complex mechanical systems in mechanical engineering automotive engineering aerospace engineering and biomechanics The presentation focuses on the implicit and explicit mathematical formulations of the bonds that geometrically constrain the motion of the partial bodies and define the directions of the reaction forces and reaction moments This results in a consistent and common approach to the various known forms of the equations of motion of multibody systems In addition to open multibody systems with a tree structure closed multibody systems with kinematic loops are also treated in detail In the third edition planar multibody systems are presented in a separate chapter to facilitate the transition from mass point systems to spatial multibody systems

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