

1/1

$$a) m = \frac{W}{g} = \frac{3600}{32.2} = 111.8 \text{ slugs}$$

$$b) W = 3600 \text{ lb} \left[ \frac{4.4482 \text{ N}}{\text{lb}} \right] = 16,010 \text{ N}$$

$$c) m = \frac{W}{g} = \frac{16,010}{9.81} = 1632 \text{ kg}$$

$$\left( \text{or } m = 111.8 \text{ slugs} \left[ \frac{14.594 \text{ kg}}{\text{slug}} \right] = 1632 \text{ kg} \right)$$

1/2

For a 180-lb person:

$$W = mg : 180 \text{ lb} = m (32.2 \text{ ft/sec}^2)$$

$$180 \text{ lb} \left( \frac{4.4482 \text{ N}}{\text{lb}} \right) = 801 \text{ N}$$

$$W = mg : 801 \text{ N} = m (9.81 \text{ m/s}^2)$$

$$m = 81.6 \text{ kg}$$

1/3

$$\underline{V_1} = 15 \left( \frac{4}{5} \underline{i} + \frac{3}{5} \underline{j} \right) = 12 \underline{i} + 9 \underline{j}$$

$$\underline{V_2} = 12 (-\cos 60^\circ \underline{i} + \sin 60^\circ \underline{j}) = -6 \underline{i} + 10.39 \underline{j}$$

$$\underline{V_1} + \underline{V_2} = 15 + 12 = 27$$

$$\underline{V_1} + \underline{V_2} = (12-6) \underline{i} + (9+10.39) \underline{j} = 6 \underline{i} + 19.39 \underline{j}$$

$$\underline{V_1} - \underline{V_2} = (12-(-6)) \underline{i} + (9-10.39) \underline{j} = 18 \underline{i} - 1.39 \underline{j}$$

$$\underline{V_1} \times \underline{V_2} = (12 \underline{i} + 9 \underline{j}) \times (-6 \underline{i} + 10.39 \underline{j})$$

$$= (24.7 + 54) \underline{k} = 178.7 \underline{k}$$

$$\underline{V_2} \times \underline{V_1} = -(\underline{V_1} \times \underline{V_2}) = -178.7 \underline{k}$$

$$\underline{V_1} \cdot \underline{V_2} = (12 \underline{i} + 9 \underline{j}) \cdot (-6 \underline{i} + 10.39 \underline{j})$$

$$= 12(-6) + 9(10.39) = 21.5$$

1/4

The weight of an average apple is

$$W = \frac{5 \text{ lb}}{12 \text{ apples}} = 0.417 \text{ lb}$$

$$\text{Mass in slugs is } m = \frac{W}{g} = \frac{0.417}{32.2} = 0.01294 \text{ slugs}$$

$$\text{Mass in kg is } m = 0.01294 \text{ slugs} \left( \frac{14.594 \text{ kg}}{1 \text{ slug}} \right) = 0.1888 \text{ kg}$$

$$\text{Weight in N is } W = mg = 0.1888 (9.81) = 1.853 \text{ N}$$

These apples weigh closer to 2 N each than to the rule of 1 N each!

1/5

Mass of iron sphere  $m = \rho V$ 

$$= (7210 \frac{\text{kg}}{\text{m}^3}) \left( \frac{4}{3} \pi (0.05)^3 \right) = 3.78 \text{ kg}$$

Force of mutual attraction:  $\frac{Gm^2}{d^2}$ Weight of each sphere:  $\frac{Gm_0 m}{r^2}$ 

$$\begin{aligned} \frac{Gm^2}{d^2} &= \frac{Gm_0 m}{r^2}, \quad r = d \sqrt{\frac{m_0}{m}} \\ &= 0.1 \sqrt{\frac{2.4 \times 10^3 \text{ kg}}{3.78}} \left( \frac{1}{20} \right) \\ &= 1.258 (10^{-3}) \text{ km} \end{aligned}$$

1/6



$$\begin{aligned} F_B &= \frac{Gm_1 m_2}{d_{AB}^2} = \frac{G \left( \rho \frac{4}{3} \pi r^3 \right) \left( \rho \frac{4}{3} \pi r^3 \right)}{d_{AB}^2} \\ &= \frac{6.673 (10^{-11}) \left[ \frac{4}{3} \pi (0.050)^3 \right]^2 (8710)(2670)}{1^2} \end{aligned}$$

$$= 4.38 (10^{-10}) \text{ N}$$

$$\begin{aligned} F_C &= \frac{Gm_1 m_0}{d_{AC}^2} = \frac{G \left[ \frac{4}{3} \pi r^3 \right]^2 \rho_0 \rho_c}{d_{AC}^2} \\ &= \frac{6.673 (10^{-11}) \left[ \frac{4}{3} \pi (0.050)^3 \right]^2 (8710)(7210)}{1^2} \end{aligned}$$

$$= 1.175 (10^{-9}) \text{ N}$$

$$\begin{aligned} \underline{R} &= \underline{F_B} + \underline{F_C} = 4.38 (10^{-10}) [-\sin 30^\circ \underline{i} + \cos 30^\circ \underline{j}] \\ &\quad + 1.175 (10^{-9}) [\sin 30^\circ \underline{i} + \cos 30^\circ \underline{j}] \end{aligned}$$

$$\underline{R} = (3.68 \underline{i} + 13.98 \underline{j}) 10^{-10} \text{ N}$$

1/7

$$\begin{aligned} \underline{g_h} &= \frac{Gm_0}{(R+h)^2} \\ &= \frac{(3.438 \times 10^{-25}) (4.075 \times 10^{22})}{[(3151)(5220) + (150)(5220)]^2} = 2.11 \text{ ft/sec}^2 \end{aligned}$$

$$\text{Mass of man: } m = \frac{W}{g} = \frac{250}{32.174} = 6.22 \text{ slugs}$$

Absolute weight at  $h = 150$  miles:

$$W_h = mg_h = (6.22)(2.11) = 132.0 \text{ lb}$$

The terms "zero-g" and "weightless" are definitely misnomers in this instance.

1/8

$$mg = 0.1 mg_0$$

$$\frac{R^2}{(R+h)^2} g_0 = 0.1 g_0$$

$$\text{Solve for } h \text{ to obtain } h = 2.16R$$

# Meriam Dynamics 6th Edition Solution

**S Baum**



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**Parallel Robots** Hamid D. Taghirad,2013-02-20 Parallel structures are more effective than serial ones for industrial automation applications that require high precision and stiffness or a high load capacity relative to robot weight Although many industrial applications have adopted parallel structures for their design few textbooks introduce the analysis of such robots in terms of dynamics and control Filling this gap *Parallel Robots Mechanics and Control* presents a systematic approach to analyze the kinematics dynamics and control of parallel robots It brings together analysis and design tools for engineers and researchers who want to design and implement parallel structures in industry Covers Kinematics Dynamics and Control in One Volume The book begins with the representation of motion of robots and the kinematic analysis of parallel manipulators Moving beyond static positioning it then examines a systematic approach to performing Jacobian analysis A special feature of the book is its detailed coverage of the dynamics and control of parallel manipulators The text examines dynamic analysis using the Newton Euler method the principle of virtual work and the Lagrange formulations Finally the book elaborates on the control of parallel robots considering both motion and force control It introduces various model free and model based controllers and develops robust and adaptive control schemes It also addresses redundancy resolution schemes in detail Analysis and Design Tools to Help You Create Parallel Robots In each chapter the author revisits the same case studies to show how the techniques may be applied The case studies include a planar cable driven parallel robot part of a promising new generation of parallel structures that will allow for larger workspaces The MATLAB code used for analysis and simulation is available online Combining the analysis of kinematics and dynamics with methods of designing controllers this text offers a holistic introduction for anyone interested in designing and implementing parallel robots *Computers in Engineering* ,1989 The Education Index ,1959

**Principles of Engineering Mechanics** Millard F. Beatty Jr.,2013-12-18 Separation of the elements of classical mechanics into kinematics and dynamics is an uncommon tutorial approach but the author uses it to advantage in this two volume set Students gain a mastery of kinematics first a solid foundation for the later study of the free body formulation of the dynamics problem A key objective of these volumes which present a vector treatment of the principles of mechanics is to help the student gain confidence in transforming problems into appropriate mathematical language that may be manipulated to give useful physical conclusions or specific numerical results In the first volume the elements of vector calculus and the matrix algebra are reviewed in appendices Unusual mathematical topics such as singularity functions and some elements of tensor analysis are introduced within the text A logical and systematic building of well known kinematic concepts theorems and formulas

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Engineering Dynamics Oliver M. O'Reilly, 2013-03-09 Scope Aims and Audiences This primer is intended to provide the theoretical background for the standard undergraduate course in dynamics This course is usually based on one of the following texts Bedford and Fowler 6 Beer and John ston 7 Hibbeler 33 Meriam and Kraige 39 Riley and Sturges 50 and Shames 56 among others Although most teachers will have cer tain reservations about these texts there appears to be a general consensus that the selection of problems each of them presents is an invaluable and essential aid for studying and understanding dynamics I myself use Meriam and Kraige 39 when teaching such a course which is referred to as ME104 at the University of California at Berkeley However I have found that the gap between the theory presented in the aforementioned texts and the problems I wished my students to solve was too large As a result I prepared my own set of notes on the relevant theory and I used Meriam and Kraige 39 as a problem and homework resource This primer grew out of these notes Its content was also heavily influenced by three other courses that I teach one on rigid body dynamics one on La 1 grangian mechanics and another on Hamiltonian mechanics Because I use the primer as a supplement I have only included a set of brief exercises at the end of each chapter

**Meriam's Engineering Mechanics** James L. Meriam, L. Glenn Kraige, J. N. Bolton, L. G. Kraige, 2020-03-17 Known for its accuracy clarity and dependability Meriam Kraige and Bolton s Engineering Mechanics Statics 9th Edition has provided a solid foundation of mechanics principles for more than 60 years This text continues to help students develop their problem solving skills with an extensive variety of engaging problems related to engineering design In addition to new homework problems the text includes a number of helpful sample problems To help students build necessary visualization and problem solving skills the text strongly emphasizes drawing free body diagrams one of the most important skills needed to solve mechanics problems

Journal of Dynamic Systems, Measurement, and Control , 2000 Publishes theoretical and applied original papers in dynamic systems Theoretical papers present new theoretical developments and knowledge for controls of dynamical systems together with clear engineering motivation for the new theory Applied papers include modeling simulation and corroboration of theory with emphasis on demonstrated practicality

**The International Journal of Mechanical Engineering Education** , 1978 **Subject Guide to Books in Print** , 1996 **Engineering Mechanics: Statics, Australian New Zealand Edition** James L. Meriam, L. Glenn Kraige, Jeff

N. Bolton, 2019-07-09 A foundation in mechanics principles with integrated engineering design problems Recognized for its accuracy and reliability Engineering Mechanics Statics has provided a solid foundation of mechanics principles for decades The ninth edition helps students develop problem solving skills This text for Australia and New Zealand includes helpful sample and practice problems It guides students in developing visualization and problem solving skills by focusing on the drawing of free body diagrams a key skill for solving mechanics problems Scientific and Technical Books in Print , 1972

FORENSIC ENGINEERING RECONSTRUCTION OF ACCIDENTS John Fiske Brown, Kenneth S. Obenski, Thomas R. Osborn, 2003-01-01 This book is not an advanced engineering text Rather it is a practical presentation with traffic accident reconstruction principles presented in a simple understandable manner so that the reader will easily retain these important concepts The engineering principles involved are introduced at the elementary level and in many cases equations used in freshman physics are derived The authors believe that the derivations are presented in the simplest manner possible so that the reader will retain this material The book is the result of an effort to compile over a period of years useful forensic engineering data information and analytical techniques over and above those taught to non engineers Many of the mathematical treatments are original In general the book reflects the authors combined over forty years experience of forensic investigations involving thousands of cases It offers something for everyone interested in forensic engineering In the new second edition Chapters 3 to 5 have been substantially modified and the remainder of the text has been edited to bring its various parts up to date The experienced investigator will find a wealth of new ideas and relationships to fill in gaps in his knowledge and reinforce his analytical approaches Those starting new in this work will have an advantage on their competition after studying this material For the non technical reader most of the book is eminently readable To an investigator attorney or insurance adjuster with only a nodding acquaintance with freshman physics the book should be totally comprehensible

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