

Contents

1	Basics	1
1.1	Introduction	1
1.2	Modeling	1
1.3	Basic Concepts	3
1.3.1	Mass	3
1.3.2	Euler's Cut Principle and Forces	4
1.3.3	Constraints	5
1.3.4	Virtual Displacements	9
1.4	Kinematics	10
1.4.1	Coordinate Systems and Coordinates	10
1.4.2	Transformation of Coordinates	15
1.4.3	Relative Kinematics	16
1.5	Momentum and Moment of Momentum	22
1.5.1	General Axioms	22
1.5.2	Momentum	23
1.5.3	Moment of Momentum	24
1.6	Energy	25
1.7	Principles of d'Alembert and Jourdain	27
1.7.1	Significance of Constraints	27
1.7.2	Principle of d'Alembert	28
1.7.3	Principle of Jourdain	31
1.8	Newton-Euler Equations for Constrained Systems	33
1.8.1	Single Rigid Body	33
1.8.2	System with Multiple Rigid Bodies	35
1.8.3	Remarks	35
1.9	Lagrange's Equations	40
1.9.1	Lagrange's Equations of the First Kind	40
1.9.2	Lagrange's Equations of the Second Kind	44
1.10	Hamilton's Equations	55
1.10.1	Hamilton's Principle	55
1.10.2	Hamilton's Canonical Equations	57

1.11	Practical Considerations	59
2	Linear Discrete Models	69
2.1	Linearization	69
2.2	Classification of Linear Systems	71
2.3	Solution Methods	76
2.3.1	Linear Second-Order Systems	77
2.3.2	Linear First-Order Systems	83
2.4	Stability of Linear Systems	98
2.4.1	Criteria Based on the Characteristic Polynomial	98
2.4.2	Stability of Mechanical Systems	101
3	Linear Continuous Models	103
3.1	Models of Continuous Oscillators	103
3.2	Simple Examples of Continuous Vibrations	104
3.2.1	Beam as a Bending Vibrator	104
3.2.2	Beam as a Bending Vibrator with an End Mass	109
3.2.3	Beam as a Torsional Vibrator with an End Mass	112
3.2.4	Transverse Vibrations of a String	115
3.3	Approximation of Continuous Vibration Systems	117
3.3.1	Function Systems and Completeness	117
3.3.2	Rayleigh-Ritz Method	119
3.3.3	Bubnov-Galerkin Method	123
3.3.4	Boundary Conditions for the Rayleigh-Ritz and Bubnov-Galerkin Method	127
3.3.5	Choice of Trial Functions	129
3.3.6	Bending Vibrations of a Beam with Longitudinal Load ...	129
3.4	Vibrations of Elastic Multibody Systems	135
4	Methods for Nonlinear Mechanics	137
4.1	General Remarks	137
4.2	Phase Space	138
4.3	A 1-DOF Nonlinear Oscillator	140
4.3.1	Piecewise Exact Solution	143
4.3.2	Method of Weighted Residuals	144
4.3.3	Harmonic Balance	146
4.3.4	Method of Least Squares	147
4.3.5	Practical Example	148
4.4	Stability of Motion	151
4.4.1	General Stability Definitions	152
4.4.2	Linear Stability	155
4.4.3	Stability of Nonlinear Systems	156

5	Vibration Phenomena	165
5.1	Introduction	165
5.2	Free Vibrations	167
5.3	Forced Vibrations	170
5.4	Self-excited Vibrations	175
5.4.1	Hydraulic Oscillator	177
5.4.2	Drinking Bird	179
5.4.3	Woodpecker Toy	180
5.4.4	Friction Oscillator	181
5.4.5	Kármán Vortex Street	185
5.4.6	Flutter	187
5.4.7	Pendulum Clock	188
5.5	Parametrically Excited Vibrations	191
5.5.1	Overview	191
5.5.2	Motion and Stability of Parametrically Excited Vibrations	192
5.5.3	Examples	199
	References	207
	Index	211