

Contents

1	Introduction	1
1.1	Multibody Systems and the Advent of Computers	1
1.2	Multibody System's Equations of Motion	4
1.3	Kinematic and Dynamic Analyses of Multibody Systems	6
1.4	Multibody Systems with Imperfect Joints	7
1.5	Contact Analysis in Multibody Systems	11
	References	16
2	Multibody Systems Formulation	23
2.1	Multibody System Definition	24
2.2	Cartesian Coordinates	25
2.3	Constraints for Revolute and Translational Joints	26
2.4	Kinematic Analysis	28
2.5	Equations of Motions for a Constrained Multibody System	30
2.6	Direct Integration Method of the Equations of Motion	32
2.7	Solution Methods that Handle Constraint Violations	34
2.7.1	Baumgarte Stabilization Method	35
2.7.2	Coordinate Partitioning Method	37
2.7.3	Augmented Lagrangian Formulation	39
2.8	Application Example: Four-Bar Mechanism	40
2.9	Summary	43
	References	44
3	Contact-Impact Force Models for Mechanical Systems	47
3.1	Approaches to Contact and Impact of Rigid Bodies	47
3.2	Normal Force Models for Spherical Contact Surfaces	49
3.3	Normal Contact Force Models for Cylindrical Surfaces	54
3.4	Tangential Friction Force Models	57
3.5	Numerical Aspects in Contact Analysis	60
3.6	Summary	63
	References	64
4	Planar Joints with Clearance: Dry Contact Models	67
4.1	Clearance Models	68

4.2	Model of Revolute Joint with Clearance	70
4.3	Model of Translational Joint with Clearance	74
4.4	Application 1: Slider–Crank with Revolute Clearance Joint	80
4.5	Application 2: Slider–Crank with Translational Clearance Joint	91
4.6	Summary	98
	References	99
5	Lubricated Joints for Mechanical Systems	101
5.1	General Issues in Tribology	102
5.2	Dynamic Characteristics of Journal–Bearings	103
5.3	Hydrodynamic Forces in Dynamic Journal–Bearings	105
5.4	Transition Between Hydrodynamic and Dry Contact	110
5.5	Kinematic Aspects of the Journal–Bearing Interaction	113
5.6	Application Example 1: Simple Journal–Bearing	115
5.7	Demonstrative Example 2: Slider–Crank Mechanism	120
5.8	Summary	129
	References	130
6	Spatial Joints with Clearance: Dry Contact Models	133
6.1	Spatial Multibody Systems	134
6.2	Spherical Joint with Clearance	138
6.3	Spatial Revolute Joint with Clearance	143
6.4	Demonstrative Example 1: Four-Bar Mechanism	153
6.5	Demonstrative Example 2: Double Pendulum	158
6.6	Demonstrative Example 3: Slider–Crank Mechanism	162
6.7	Summary	168
	References	169