

3/128



Initial Max. deformation

The maximum force $F = kx$ occurs when x is a maximum with $\dot{x} = 0$.

$$U_1 + \Delta T = mgs - \frac{1}{2}kx^2 = 0, \quad x = \frac{2mg}{k}$$

$$\text{So } F = kx = 2mg$$

$$3/129 \quad T_A + V_{A-0} = T_C : 0 + 2mgR = \frac{1}{2}mv_C^2, \quad v_C^2 = 4gR$$

$$(a) \quad \Sigma F_n = ma_n : N_B = m \frac{4gR}{R} = 4mg$$

$$(b) \quad T_A + V_{A-C} = T_C : 0 + 3mgR = \frac{1}{2}mv_C^2, \quad v_C^2 = 6gR$$

$$\Sigma F_n = ma_n : N_C - mg = m \frac{6gR}{R}$$

$$N_C = 7mg$$

(c) Coll. stopping point E:

$$T_A + V_{A-E} = T_E$$

$$0 + 2mgR - mg\left(\frac{1}{2}\right) - \mu_k \frac{15}{2}mg = 0$$

$$s = \frac{4R}{1 + \mu_k 15}$$

(Note: Normal force on incline is)

$$N = mg \cos 30^\circ = \frac{\sqrt{3}}{2}mg$$

3/130 Let s = distance down incline before reversal of direction.

$$U_1 + \Delta T = 100(2)(10 + s - s) - 200(10 + s - s)\frac{5}{13} = 1046 \text{ ft}\cdot\text{lb}$$

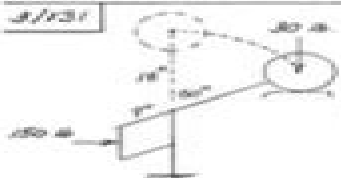
$$\Delta T = \frac{1}{2} \frac{350}{32.2} [v^2 - (17)^2] = 4.66v^2 - 377 \text{ ft}\cdot\text{lb}$$

$$U_1 + \Delta T : 1046 = 4.66v^2 - 377$$

$$v = 17.45 \text{ ft/sec}$$

The initial kinetic energy is positive regardless of the velocity direction.

3/131



$$U_1 + \Delta T$$

$$150\left(\frac{1}{2}g \sin 60^\circ\right) - 30\frac{1}{2}g \sin 60^\circ$$

$$= \frac{1}{2} \frac{150}{32.2} (v^2 - 0)$$

$$v^2 = 160.8, \quad v = 12.68 \text{ m/sec}$$

$$3/132 \quad U_1 + \Delta T : mg(0.8 - 1.8 \cos 60^\circ)$$

$$= \frac{1}{2}m(12^2 - 9^2)$$

$$R(1)(0.20) = \frac{1}{2}(12^2 - 9^2), \quad 12^2 = 12.92, \quad 12 = 3.59 \text{ m/s}$$

3/133



$$+\uparrow \Sigma F = 0 : 9810 - 4T = 0, \quad T = 2450 \text{ N}$$

Length of cable $L = 4s_0 + \text{constants}$

$$L = 4v_0 = 4(3) = 12 \text{ m/s}$$

$$P_{\text{out}} = -T\dot{L} = -2450(12) = 29400 \text{ watts}$$

$$\text{or } P_{\text{out}} = 29.4 \text{ kW}$$

$$C = \frac{P_{\text{out}}}{P_{\text{in}}}, \quad P_{\text{in}} = \frac{P_{\text{out}}}{C} = \frac{29.4}{0.8}$$

$$P_{\text{in}} = 36.8 \text{ kW}$$

3/134



$$U_1 + \Delta T (\text{system})$$

$$\text{First interval: } 30(9.81)(1.2) - [30(9.81)(0.5 + 1.224)] \frac{1}{2} = \frac{1}{2} 30 v^2 + \frac{1}{2} 30 (10)^2$$

$$v^2 = 6.076 \text{ m/s}^2, \quad v = 2.447 \text{ m/s}$$

$$\text{Second interval: } 15(9.81)(2) - [30(9.81)(0.5 + 1.224)] \frac{1}{2} = 0 - \frac{1}{2} 15 (2.447)^2$$

$$- \frac{1}{2} 30 \left(\frac{5.076}{2}\right)^2$$

$$y = 2.18 \text{ m}, \quad s = \frac{1}{2}(1.2 + 2.18) = 1.69 \text{ m}$$

$$3/135 \quad U_1 + \Delta T : -\int_0^0 (3x^2 + 60x) dx = \frac{1}{2} \frac{450}{32.2} (0 - v^2) 12$$

$$x^2 + 20x^2 \Big|_0^0 = \frac{555}{32.2} v^2, \quad v \text{ in ft/sec.}$$

$$v^2 = \frac{32.2}{555} (60 + 480) = 60.82 \text{ (ft/sec)}^2, \quad v = 7.80 \text{ ft/sec}$$

$$3/136 \quad \Theta = \tan^{-1} \frac{6}{100} = 3.43^\circ$$

$$U_1 + \Delta T : U_1 + mgh = \frac{1}{2} m (v_1^2 + v_2^2)$$

$$U_1 = -1400(9.81)(200 \sin 3.43^\circ)$$

$$+ \frac{1}{2} 1400 \left[\left(\frac{20}{5.28}\right)^2 + \left(\frac{100}{5.28}\right)^2 \right]$$

$$= -683,000 \text{ J or } -683 \text{ kJ}$$

$$\text{Energy lost } Q = 683 \text{ kJ}$$

3/137 The power output of the drivetrain is

$$P_{\text{out}} = Fv = 540 \left(\frac{30}{3.6}\right) = 14,400 \text{ W}$$

The power input to the drivetrain:

$$P_{\text{in}} = \frac{P_{\text{out}}}{\epsilon} = \frac{14,400}{0.70} = 20,571 \text{ W}$$

$$\text{So the motor output } P = 20.6 \text{ kW}$$

Meriam Kraige Engineering Mechanics Dynamics 7th Solutions

James L. Meriam, L. G. Kraige



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Books in Print Supplement, 1994

XVIII International Coal Preparation Congress Vladimir Litvinenko, 2016-10-21 This book gathers technical and scientific articles by leading experts from 15 countries and originally presented at the world's most prestigious forum on coal

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Climbing and Walking Robots Manuel Armada, Pablo González de Santos, 2006-01-16 Interest in climbing and walking robots CLAWAR has increased remarkably over recent years Novel solutions for complex and very diverse application fields exploration intervention in severe environments personal services emergency rescue operations transportation entertainment medical etc have been anticipated by great progress in this area of robotics This book contains the proceedings of the 7th Climbing and Walking Robots 2004 CLAWAR 2004 Conference offering the international scientific community one of the most excellent forums for academics researchers and industrialists interested in this motivating area of climbing and walking robots It provides a wide forum of original state of the art contributions from various industrial and new emerging research fields presenting a full picture of climbing and walking robots The conference held in Madrid Spain September 22 24 2004 was organized by the Thematic Network CLAWAR 2 and funded by the European Commission under the GROWTH Program

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A Primer in Fluid Mechanics Dynamics of Flows in One Space Dimension Jr. Brower, 2024-11-01 This distinctive text presents the basic principles of fluid mechanics by means of one dimensional flow examples differing significantly in style and content from other books A Primer in Fluid

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Table of Contents Meriam Kraige Engineering Mechanics Dynamics 7th Solutions

1. Understanding the eBook Meriam Kraige Engineering Mechanics Dynamics 7th Solutions
 - The Rise of Digital Reading Meriam Kraige Engineering Mechanics Dynamics 7th Solutions
 - Advantages of eBooks Over Traditional Books
2. Identifying Meriam Kraige Engineering Mechanics Dynamics 7th Solutions
 - Exploring Different Genres
 - Considering Fiction vs. Non-Fiction
 - Determining Your Reading Goals
3. Choosing the Right eBook Platform
 - Popular eBook Platforms
 - Features to Look for in an Meriam Kraige Engineering Mechanics Dynamics 7th Solutions
 - User-Friendly Interface
4. Exploring eBook Recommendations from Meriam Kraige Engineering Mechanics Dynamics 7th Solutions
 - Personalized Recommendations
 - Meriam Kraige Engineering Mechanics Dynamics 7th Solutions User Reviews and Ratings

- Meriam Kraige Engineering Mechanics Dynamics 7th Solutions and Bestseller Lists
- 5. Accessing Meriam Kraige Engineering Mechanics Dynamics 7th Solutions Free and Paid eBooks
 - Meriam Kraige Engineering Mechanics Dynamics 7th Solutions Public Domain eBooks
 - Meriam Kraige Engineering Mechanics Dynamics 7th Solutions eBook Subscription Services
 - Meriam Kraige Engineering Mechanics Dynamics 7th Solutions Budget-Friendly Options
- 6. Navigating Meriam Kraige Engineering Mechanics Dynamics 7th Solutions eBook Formats
 - ePub, PDF, MOBI, and More
 - Meriam Kraige Engineering Mechanics Dynamics 7th Solutions Compatibility with Devices
 - Meriam Kraige Engineering Mechanics Dynamics 7th Solutions Enhanced eBook Features
- 7. Enhancing Your Reading Experience
 - Adjustable Fonts and Text Sizes of Meriam Kraige Engineering Mechanics Dynamics 7th Solutions
 - Highlighting and Note-Taking Meriam Kraige Engineering Mechanics Dynamics 7th Solutions
 - Interactive Elements Meriam Kraige Engineering Mechanics Dynamics 7th Solutions
- 8. Staying Engaged with Meriam Kraige Engineering Mechanics Dynamics 7th Solutions
 - Joining Online Reading Communities
 - Participating in Virtual Book Clubs
 - Following Authors and Publishers Meriam Kraige Engineering Mechanics Dynamics 7th Solutions
- 9. Balancing eBooks and Physical Books Meriam Kraige Engineering Mechanics Dynamics 7th Solutions
 - Benefits of a Digital Library
 - Creating a Diverse Reading Collection Meriam Kraige Engineering Mechanics Dynamics 7th Solutions
- 10. Overcoming Reading Challenges
 - Dealing with Digital Eye Strain
 - Minimizing Distractions
 - Managing Screen Time
- 11. Cultivating a Reading Routine Meriam Kraige Engineering Mechanics Dynamics 7th Solutions
 - Setting Reading Goals Meriam Kraige Engineering Mechanics Dynamics 7th Solutions
 - Carving Out Dedicated Reading Time
- 12. Sourcing Reliable Information of Meriam Kraige Engineering Mechanics Dynamics 7th Solutions
 - Fact-Checking eBook Content of Meriam Kraige Engineering Mechanics Dynamics 7th Solutions
 - Distinguishing Credible Sources

13. Promoting Lifelong Learning
 - Utilizing eBooks for Skill Development
 - Exploring Educational eBooks
14. Embracing eBook Trends
 - Integration of Multimedia Elements
 - Interactive and Gamified eBooks

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