

2/175 $\theta = \omega t = \frac{20}{180} \pi = 0.698 \text{ rad/s}$
 $\dot{\theta} = \frac{20}{180} \pi = 0.1745 \text{ rad/s}$
 $\ddot{\theta} = \frac{20}{180} \pi = 0.149 \text{ rad/s}^2$
 Use cylindrical coordinates
 $r = \theta \cos \beta + c \sin \beta$, $\dot{r} = (-\dot{\theta} \sin \beta + c \cos \beta) \dot{\beta}$
 $\ddot{r} = (-\ddot{\theta} \sin \beta - c \cos \beta) \dot{\beta}^2 + (-\dot{\theta} \cos \beta + c \sin \beta) \ddot{\beta}$
 $\dot{\theta} = \dot{\theta}$, $\dot{\beta} = \dot{\beta}$, $\ddot{\theta} = \ddot{\theta}$, $\ddot{\beta} = \ddot{\beta}$
 $\ddot{r} = (-\dot{\theta} \sin \beta + c \cos \beta) \dot{\beta}^2 + (-\ddot{\theta} \sin \beta - c \cos \beta) \ddot{\beta}$
 For $\beta = 90^\circ$, $\ddot{r} = (-300 \times 0.5 + 200 \times 0.956)(0.1745)^2 = 4.050 \text{ m/s}^2$
 $\ddot{r} = (-300 \times 0.956 - 200 \times 0.5)(0.1745)^2 = -2.860 \text{ m/s}^2$
 $\ddot{r} = (-300 \times 0.5 + 200 \times 0.956)(0.1745)^2 = 4.050 \text{ m/s}^2$
 $\ddot{r} = (-300 \times 0.956 - 200 \times 0.5)(0.1745)^2 = -2.860 \text{ m/s}^2$
 $a_r = \ddot{r} - r\dot{\theta}^2 = 0 - 1 \sin \beta (K)^2 = -K^2 L \sin \beta$
 $a_\theta = r\ddot{\theta} + 2\dot{r}\dot{\theta} = 0 + 2c \sin \beta (K) = 2Kc \sin \beta$
 $a_\beta = \ddot{\beta} = 0$
 $a = \sqrt{(-K^2 L \sin \beta)^2 + (2Kc \sin \beta)^2} = K \sin \beta \sqrt{K^2 L^2 + 4c^2}$

2/176 $a_r = \ddot{r} - r\dot{\theta}^2 = 0 - r\omega^2$
 $a_\theta = r\ddot{\theta} + 2\dot{r}\dot{\theta} = 0 + 0 = 0$
 $a_\phi = \frac{d}{dt}(L \sin \phi \omega) = -L \omega^2 \sin \phi$
 $a = \sqrt{(-r\omega^2)^2 + (-L \omega^2 \sin \phi)^2}$
 $a_{\max} = \sqrt{r^2 \omega^2 + L^2 \omega^2 \sin^2 \phi}$

2/177 Helix angle is $\gamma = \tan^{-1} \frac{10}{24} = 22.5^\circ$
 $v = 15 \left(\frac{5280}{3600} \right) = 22 \text{ ft/sec}$
 $v_x = v \sin \gamma = 22 \sin 22.5^\circ = 8.47 \text{ ft/sec}$
 $v_y = v \cos \gamma = 22 \cos 22.5^\circ = 20.2 \text{ ft/sec}$
 From $v_x = r\dot{\theta}$, $\dot{\theta} = \frac{v_x}{r} = \frac{8.47}{24} = 0.353 \text{ rad/sec}$
 $a_{x2} = 2 \left(\frac{5280}{3600} \right) = 2.93 \text{ ft/sec}^2$
 $a_y = -2.93 \cos 22.5^\circ = -2.71 \text{ ft/sec}^2$
 $a_z = -2.93 \sin 22.5^\circ = -1.10 \text{ ft/sec}^2$
 $a_r = \ddot{r} - r\dot{\theta}^2 = 0 - 24(0.353)^2 = -3.02 \text{ ft/sec}^2$

2/178 $\beta = \tan^{-1} \frac{1}{2} = 26.6^\circ$
 $\phi = \tan^{-1} \frac{3}{4} = 36.9^\circ$
 $v_R = 400 \sin 26.6^\circ \sin 36.9^\circ$
 $= 92.0 \text{ km/h} = R$
 $\dot{\theta} = 0.1788 \text{ rad/s}$
 $\dot{\phi} = 0.4731 \text{ rad/s}$

2/179 $v_r = \dot{r} \sin \beta = c \sin \beta$
 $v_\theta = r\dot{\theta} = (L \sin \beta) K = K L \sin \beta$
 $v_\phi = \dot{\phi} \cos \beta = c \cos \beta$
 $a = \sqrt{(-K^2 L \sin \beta)^2 + (2Kc \sin \beta)^2} = K \sin \beta \sqrt{K^2 L^2 + 4c^2}$

2/180 $\theta = \omega t = \frac{\pi}{2} t$
 $\dot{\theta} = \frac{\pi}{2}$
 $x' = r \cos \theta$
 $y' = r \sin \theta$
 $z' = 0$
 $\dot{x}' = -r\dot{\theta} \sin \theta$
 $\dot{y}' = r\dot{\theta} \cos \theta$
 $\dot{z}' = 0$
 $\ddot{x}' = -r\dot{\theta}^2 \cos \theta$, $\ddot{y}' = -r\dot{\theta}^2 \sin \theta$, $\ddot{z}' = 0$
 Component relationship:
 $x = x' \cos 30^\circ + z' \sin 30^\circ$
 $y = y'$
 $z = -x' \sin 30^\circ + z' \cos 30^\circ$
 Thus $\frac{dx}{dt} = -\frac{r}{2} \dot{\theta} \sin \frac{\pi}{2} t$, $\frac{dy}{dt} = r \dot{\theta} \cos \frac{\pi}{2} t$, $\frac{dz}{dt} = -\frac{r}{2} \dot{\theta} \cos \frac{\pi}{2} t$
 $\ddot{x} = -\frac{r}{2} \dot{\theta}^2 \sin \frac{\pi}{2} t$, $\ddot{y} = r \dot{\theta}^2 \cos \frac{\pi}{2} t$, $\ddot{z} = \frac{r}{2} \dot{\theta}^2 \cos \frac{\pi}{2} t$
 Note that position relationships do not include the constants associated with the origin position.

2/181 $f = 1200 \text{ m}$
 $R = 1000 \text{ m}$
 $\phi = \tan^{-1} \frac{400}{1000} = 21.8^\circ$
 $a = \frac{v^2}{r} = \frac{(600/3.6)^2}{1200} = 23.1 \text{ m/s}^2$
 $R = 0$, $\dot{\theta} = 0$, $\ddot{\theta} = \frac{v_R}{R \cos \beta} = \frac{600(1000)/3.6}{1000} = 0.1667 \text{ s}^{-2}$
 Eqs. 2/19: $a_R = \ddot{R} - R\dot{\theta}^2 - R\ddot{\theta} \cos \beta$
 $23.1 \sin 21.8^\circ = \ddot{R} - 0 - \frac{1000}{\cos 21.8^\circ} (0.1667)^2 \cos 21.8^\circ$
 $\ddot{R} = 34.4 \text{ m/s}^2$
 $a_\phi = \frac{1}{R} \frac{d}{dt}(R^2 \dot{\phi}) + R\dot{\phi}^2 \sin \beta \cos \beta = 2\dot{R}\dot{\phi} + R\dot{\phi}^2 \sin \beta \cos \beta$
 $23.1 \cos 21.8^\circ = 0 + \frac{1000}{\cos 21.8^\circ} \dot{\phi} + \frac{1000}{\cos 21.8^\circ} 0.1667^2 \sin 21.8^\circ \cos 21.8^\circ$
 $\dot{\phi} = 0.01038 \text{ rad/s}^2$

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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

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