

Contents

Preface	8
General notation	9
Chapter 1 Introduction	11
Chapter 2 The vibrations of systems having one degree of freedom	19
2.1 Free undamped vibration	20
2.1.1 Translational vibration	20
2.1.2 Torsional vibration	23
2.1.3 Non-linear spring element	25
2.1.4 Energy methods for analysis	30
2.1.4.1 The vibration of systems with heavy springs	31
2.1.4.2 Transverse vibration of beams	32
2.1.5 The stability of vibrating systems	35
2.2 Free damped vibration	38
2.2.1 Vibration with viscous damping	38
2.2.2 Vibration with coulomb (dry friction) damping	44
2.2.3 Vibration with combined viscous and coulomb damping ...	47
2.2.4 Vibration with hysteretic damping	48
2.2.5 Energy dissipated by damping	49
2.3 Forced vibration	52
2.3.1 Response of a viscous damped system to a simple harmonic exciting force with constant amplitude	52
2.3.2 Response of a viscous damped system supported on a foundation subjected to harmonic vibration	57
2.3.2.1 Vibration isolation	58
2.3.3 Response of a coulomb damped system to a simple harmonic exciting force with constant amplitude	67
2.3.4 Response of a hysteretically damped system to a simple harmonic exciting force with constant amplitude	68
2.3.5 Response of a system to a suddenly applied force	68

2.3.6 Shock excitation	70
2.3.7 Wind or current excited oscillation	72
2.3.8 Harmonic analysis	73
2.3.9 The measurement of vibration	76
Chapter 3 The vibrations of systems having more than one degree of freedom ..	78
3.1 The vibration of systems with two degrees of freedom	78
3.1.1 Free vibration of an undamped system	78
3.1.2 Free motion	83
3.1.3 Coordinate coupling	83
3.1.4 Forced vibration	86
3.1.5 The undamped dynamic vibration absorber	89
3.1.6 System with viscous damping	93
3.1.7 The damped dynamic vibration absorber	94
3.2 The vibration of systems with more than two degrees of freedom	97
3.2.1 The matrix method	98
3.2.1.1 Orthogonality of the principal modes of vibration ..	100
3.2.2 The Lagrange equation	103
3.2.3 Receptances	106
3.2.4 Impedance and Mobility	111
Chapter 4 The vibrations of systems with distributed mass and elasticity	117
4.1 Wave motion	117
4.1.1 Transverse vibration of a string	117
4.1.2 Longitudinal vibration of a thin uniform bar	118
4.1.3 Torsional vibration of a uniform shaft	119
4.1.4 Solution of the wave equation	119
4.2 Transverse vibration	122
4.2.1 Transverse vibration of a uniform beam	122
4.2.2 The whirling of shafts	125
4.2.3 Rotary inertia and shear effects	126
4.2.4 The effect of axial loading	126
4.2.5 Transverse vibration of a beam with discrete bodies	127
4.2.6 Receptance analysis	128
4.3 The analysis of continuous systems by Rayleigh's energy method	132
4.4 Transverse vibration of thin uniform plates	136
4.5 The finite element method	140
Chapter 5 Automatic position control systems	141
5.1 Introduction	141
5.2 Remote position control systems	146
5.3 The hydraulic servomechanism	147
5.3.1 Introduction	147
5.3.2 The open loop hydraulic servo	148
5.3.3 The closed loop hydraulic servo	150
5.3.4 Fluid leakage and compressibility effects	154
5.4 Modifications to the closed loop hydraulic servo	154

5.4.1 Derivative control	154
5.4.2 Integral control	156
5.5 The electric position servomechanism	159
5.5.1 Introduction	159
5.5.2 The closed loop servo	159
5.5.3 Servo with negative output velocity feedback	165
5.5.4 Servo with derivative of error control	165
5.5.5 Servo with integral of error control	166
5.5.6 Comparison of the main forms of the electric position servo	167
Chapter 6 Stability and frequency response of control systems	171
6.1 Introduction	171
6.2 The Laplace transformation	171
6.3 System Transfer Functions	174
6.4 Stability of control systems	177
6.4.1 The Root Locus technique	177
6.4.2 The Routh–Hurwitz criterion	190
6.5 Frequency response of control systems	191
6.5.1 The Nyquist plot	191
6.5.2 Bode analysis	201
Chapter 7 Problems	206
7.1 Systems having one degree of freedom	206
7.2 Systems having more than one degree of freedom	218
7.3 Systems with distributed mass and elasticity	237
7.4 Automatic position control systems	242
7.5 Stability and frequency response of control systems	247
7.6 Answers to selected problems	256
Index	263