

Contents

Part I Vibration of Systems with One Degree of Freedom

1	The Equation of Motion of Systems with One Degree of Freedom	3
1.1	Why Study Vibrations?	3
1.2	The Classical Oscillator	5
1.2.1	A Demonstration	5
1.2.2	Building a Model	6
1.2.3	Equilibrium Position	10
1.2.4	Energy Considerations	12
1.2.5	Damping	15
1.3	The Simple Pendulum	17
1.3.1	A Model for the Simple Pendulum	18
1.3.2	Simulating the Motion	22
1.3.3	Small Oscillation Approximation	24
1.3.4	The Damped Pendulum	27
1.4	Form of the Equation of Motion	30
1.5	Illustrative Examples	33
1.5.1	A Rolling Cylinder	33
1.5.2	Motion of a Metronome	42
1.6	Summary	50
1.7	Problems	51
2	Free Vibration of Systems with One Degree of Freedom	55
2.1	What Is Free Vibration?	55
2.2	Free Vibration of Undamped Systems	56
2.2.1	The Harmonic Oscillator	56
2.2.2	General Case of Undamped Free Vibration	61
2.2.3	Illustrative Examples	61
2.3	Free Vibration in the Presence of Viscous Damping	79
2.3.1	The Mass-Spring-Damper System	79
2.3.2	Illustrative Examples	84

2.4	Summary	89
2.5	Problems	90
3	Forced Vibration of Systems with One Degree of Freedom	95
3.1	The Forced Vibration Problem	95
3.2	Representation of Harmonic Excitation	98
3.3	Response of Undamped Systems Subjected to Harmonic Force	99
3.3.1	Computing the Response	99
3.3.2	The Frequency Response Function	100
3.3.3	Beating and Resonance	104
3.4	Response of Damped Systems Subjected to Harmonic Force	107
3.4.1	Particular Solution and the Frequency Response Function	107
3.4.2	Steady-State Response	110
3.4.3	Response Dependence on the Driving Frequency	111
3.5	Illustrative Examples	114
3.5.1	An Oscillating Bar	114
3.5.2	Exciting a Mass-Spring System	120
3.5.3	Exciting a Pendulum	125
3.5.4	Vehicle Suspension	128
3.5.5	Vibrations of a Washing Machine	136
3.6	Summary	140
3.7	Problems	141
 Part II Vibrations of Systems with Multiple Degrees of Freedom		
4	Equations of Motion of Systems with Multiple Degrees of Freedom ...	147
4.1	Systems with Multiple Degrees of Freedom	147
4.2	A System of Two Interconnected Particles	148
4.2.1	Kinematic Analysis	149
4.2.2	The Differential Equations of Motion	150
4.2.3	Equilibrium Positions	151
4.2.4	Arranging the Equations of Motion in the Matrix-Vector Form	152
4.2.5	Energy of the System	153
4.3	The Carts-Pendulum System	155
4.3.1	Kinematic Analysis	155
4.3.2	Obtaining the Equations of Motion	156
4.3.3	Equilibrium Positions	158
4.3.4	Simulating the Motion	159
4.3.5	Linearization	161
4.3.6	Energy of the System	164
4.3.7	Alternative Derivation of the Equations of Motion	165
4.4	General Form of the Equations of Motion	166
4.5	Illustrative Examples	169
4.5.1	An Autoparametric System	169

4.5.2	The Equations of Motion of an Airfoil	178
4.5.3	An Unrestrained System	182
4.6	Summary	187
4.7	Problems	188
5	Free and Forced Vibrations of Systems with Multiple Degrees of Freedom	195
5.1	Introduction	195
5.2	Free Vibration of Conservative Systems	197
5.2.1	A System with Two Particles	197
5.2.2	A System with Three Particles	204
5.2.3	Computing the Response of Undamped Systems	212
5.2.4	Illustrative Examples	215
5.3	Free Vibration of Damped Systems	225
5.3.1	A Damped System with Two Particles	226
5.3.2	Damped Free Vibrations	234
5.4	Forced Vibrations of MDOF Systems	236
5.4.1	A System with Two Particles Subject to a Harmonic Force	236
5.4.2	Forced Vibrations of a System with Three Particles	247
5.4.3	Forced Vibrations and the Frequency Response Function Matrix	250
5.4.4	Illustrative Example: The Dynamic Vibration Absorber	253
5.5	Modal Analysis	256
5.5.1	Decoupling the Equations of a System with Two Particles	258
5.5.2	Decoupling by Modal Analysis	263
5.5.3	Modal Analysis Applied to Damped Systems	267
5.5.4	Illustrative Examples	268
5.6	Summary	273
5.7	Problems	275
A	Complex Numbers	279
A.1	Vector Notation and Basic Algebra	279
A.2	Complex Conjugation	280
A.3	Polar Form	281
B	Linear Spaces and Vectors	283
B.1	Linear Spaces	283
B.2	Linear Independence of Vectors	284
B.2.1	Basis of a Finite Dimensional Linear Space	285
B.3	Euclidean Spaces	285
B.3.1	Orthonormal Basis	286
B.4	Cross (or Vector) Product	287
B.5	Differentiating Vectors	288

C	Matrices	289
C.1	Definition	289
C.2	Basic Matrix Algebra	290
C.2.1	Matrix and Linear Spaces	290
C.2.2	Matrix Multiplication	290
C.3	Operations with Matrices	291
C.3.1	Elementary Row/Column Operations	291
C.3.2	Transpose of a Matrix	292
C.3.3	Inverse of a Matrix	293
C.3.4	Determinant of a Matrix	293
C.4	Eigenvalues and Eigenvectors of a Matrix	294
D	Review of Newton–Euler Dynamics	297
D.1	Dynamics of a Single Particle	297
D.1.1	Dynamic Analysis Using Cartesian Coordinates	297
D.1.2	Dynamic Analysis Using Polar Coordinates	298
D.1.3	Energy Relations for a Particle	299
D.2	Dynamics of a System of Particles	300
D.2.1	Balance of Linear and Angular Momenta	300
D.2.2	Energy Relations for a System of Particles	301
D.3	Dynamics of a Rigid Body	302
D.3.1	A Rigid Body Rotating Around a Fixed Axis	302
D.3.2	A Rigid Body Undergoing General Plane Motion	305
D.3.3	Translational Motions of a Rigid Body	306
D.3.4	Energy Relations for a Rigid Body	306
D.3.5	Huygens' Theorem	307
E	Solving Initial Value Problems with MATLAB	309
E.1	Initial Value Problems	309
E.2	Some Basic Numerical Methods	310
E.3	Basic MATLAB Commands	312
E.4	Remarks on Stiff Problems	314
	Bibliography	317
	Index	321