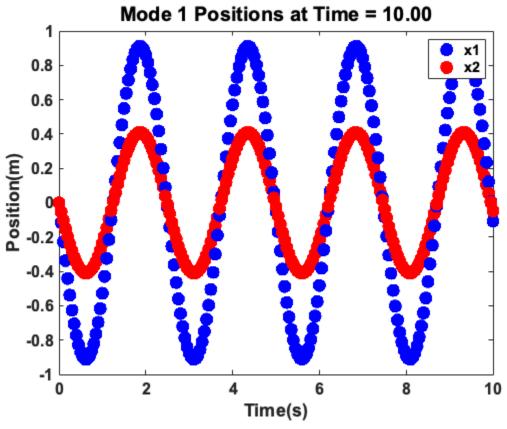
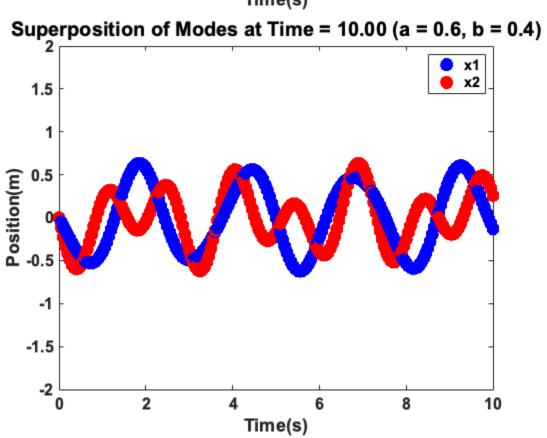
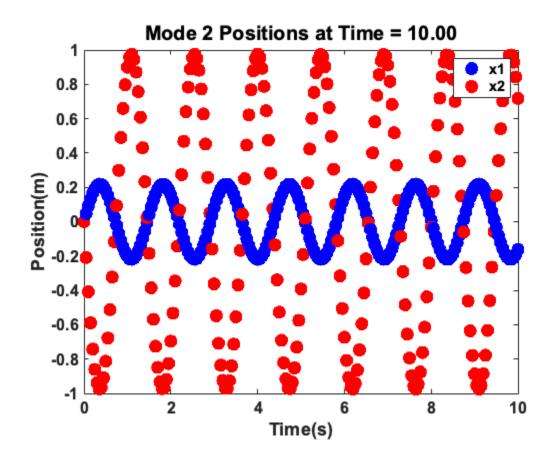
```
% Clear initials
close all;
clf;
clear variables;
clc;
clear figure;
% Given values:
m1 = 40;
m2 = 20;
k1 = 200;
k2 = 100;
k3 = 250;
% Time values:
t = 0; tFinal = 10.05; dt = 0.05;
alpha = 0.6;
beta = 0.4;
% Equations of amplitude
A = [(k1 + k2) / m1, -k2 / m1; -k2 / m2, (k2 + k3) / m2];
% Find eigenvalues and eigenvectors
[V, D] = eig(A);
lambda1 = D(1,1);
lambda2 = D(2,2);
omega1 = sqrt(lambda1);
omega2 = sqrt(lambda2);
% Find Amplitudes:
amp1lam1 = V(1,1);
amp2lam1 = V(2,1);
amp1lam2 = V(1,2);
amp2lam2 = V(2,2);
while t < tFinal
    if t+dt > tFinal
        dt = tFinal - t;
    end
```

```
% Equations of motion for mode 1:
    modelx1 = ampllam1*sin(omega1*t);
    mode1x2 = amp2lam1*sin(omega1*t);
    % Equations of motion for mode 2:
    mode2x1 = amp1lam2*sin(omega2*t);
   mode2x2 = amp2lam2*sin(omega2*t);
    % Combined equations of general motion
   x1 = alpha*amp1lam1*sin(omega1*t) + beta*amp1lam2*sin(omega2*t);
   x2 = alpha*amp2lam1*sin(omega1*t) + beta*amp2lam2*sin(omega2*t);
    % Plot motion of each mass in the first mode
    figure(1)
    plot(t, modelx1, 'b.'); hold on;
   plot(t, mode1x2, 'r.');
   xlabel('Time(s)');
    ylabel('Position(m)');
    s = sprintf('Mode 1 Positions at Time = %2.2f', t);
    title(s); legend('x1','x2');
    xlim([0 10]); ylim([-1 1]); fixfig; pause(dt);
    % Plot motion of each mass in the second mode
    figure(2)
    plot(t, mode2x1, 'b.'); hold on;
   plot(t, mode2x2, 'r.');
   xlabel('Time(s)');
   ylabel('Position(m)');
    s = sprintf('Mode 2 Positions at Time = %2.2f', t);
    title(s); legend('x1','x2');
    xlim([0 10]); ylim([-1 1]); fixfig; pause(dt);
    % Plot the combined motion of the modes
    figure(3)
   plot(t, x1, 'b.'); hold on;
   plot(t, x2, 'r.');
    xlabel('Time(s)');
    ylabel('Position(m)');
    s = sprintf('Superposition of Modes at Time = %2.2f (a = %2.1f, b =
%2.1f)',t,alpha,beta);
    title(s); legend('x1','x2');
   xlim([0 10]); ylim([-2 2]); fixfig; pause(dt);
    % Prepare for next time step
    t = t + dt;
end
```







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