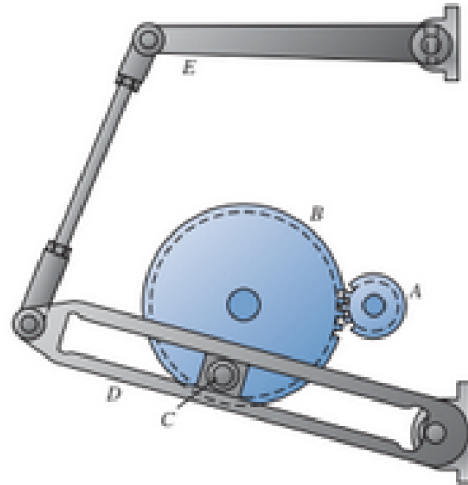


CINEMATICA MECANISMO:



```
clc
clear
close all

% Definir las constantes y variables del problema
dt = 0.01;           % Paso de tiempo en segundos
t_max = 10;          % Tiempo máximo de la simulación en segundos
t = 0:dt:t_max;      % Vector Tiempo

%Radios
rb=0.3;
ra=0.1;
rbc=rb;
rod=1.3;
rde=1.1;
rpe=1;
d=0.6;
h=0.16;
d2 = 0;
h2 =1.33;

%Angulos Iniciales Theta4 y Theta5
theta40 = pi/2;
theta50 = 2.617;

% Crear vectores para almacenar los datos de la simulación
%Longitudes
Roc=zeros(1,t_max/dt+1);
Rocx=zeros(1,t_max/dt+1);
Rocy=zeros(1,t_max/dt+1);
Roc=zeros(1,t_max/dt+1);

%Aceleraciones
Acx=zeros(1,t_max/dt+1);
```

```

Acy=zeros(1,t_max/dt+1);
Ac=zeros(1,t_max/dt+1);
Acox=zeros(1,t_max/dt+1);
Acoy=zeros(1,t_max/dt+1);
Ac_ox=zeros(1,t_max/dt+1);
Ac_oy=zeros(1,t_max/dt+1);
%Velocidades
Vcx=zeros(1,t_max/dt+1);
Vcy=zeros(1,t_max/dt+1);
Vc=zeros(1,t_max/dt+1);
Vcox=zeros(1,t_max/dt+1);
Vcoy=zeros(1,t_max/dt+1);
Vc_ox=zeros(1,t_max/dt+1);
Vc_oy=zeros(1,t_max/dt+1);

%BARRAS
%Engranaje A
Wa=zeros(1,t_max/dt+1);
alphaa=zeros(1,t_max/dt+1);
theta1=zeros(1,t_max/dt+1);
%Engranaje B
Wb=zeros(1,t_max/dt+1);
alphab=zeros(1,t_max/dt+1);
theta2=zeros(1,t_max/dt+1);

%Barra OD
alphaoc=zeros(1,t_max/dt+1);
alphaod=zeros(1,t_max/dt+1);
Woc=zeros(1,t_max/dt+1);
Wod=zeros(1,t_max/dt+1);
theta3 = zeros(1, t_max/dt+1);

%Barra DE
alphade=zeros(1,t_max/dt+1);
Wde=zeros(1,t_max/dt+1);
theta4 = zeros(1, t_max/dt+1);

%Barra PE
alphape=zeros(1, t_max/dt+1);
Wpe=zeros(1, t_max/dt+1);
theta5 = zeros(1, t_max/dt+1);

% Definir las condiciones iniciales

Wa(1)=2;
alphaa(1)=1;
theta1(1)=0;

```

```
% Realizar la simulación
```

```
for i=1:length(t)-1
```

```
%
```

```
%DATOS ENGRANAJE A:
```

```
alphaa(i)=alphaa(1)+((i*dt).^2);
```

```
Wa(i)=Wa(1)+alphaa(1)*(i*dt)+(((i*dt).^3)/3);
```

```
theta1(i)=theta1(1)+Wa(1)*(i*dt)+(1/2)*(alphaa(1))*((i*dt).^2)+(1/12)*((i*dt).^4);
```

```
%
```

```
%DATOS ENGRANAJE B:
```

```
alphanb(i)=(alphaa(1)+((i*dt).^2))*(-ra/rb);
```

```
Wb(i)=(Wa(1)+alphaa(1)*(i*dt)+(((i*dt).^3)/3))*(-ra/rb);
```

```
theta2(i)=(Woc(1)*(i*dt)+(1/2)*alphanb(1))*((i*dt).^2)+(1/12*(((i*dt).^4)))*(ra/rb);
```

```
%
```

```
%DATOS BARRA O-D
```

```
Rocx(i)=-d+rb*cos(theta2(i));
```

```
Rocy(i)=h+rb*sin(theta2(i));
```

```
Roc=[Rocx Rocy];
```

```
%Aceleracion Angular
```

```
Acx(i)=-alphanb(i)*rb*sin(theta2(i))-(Wb(i).^2)*rb*cos(theta2(i));
```

```
Acy(i)=alphanb(i)*rb*cos(theta2(i))+(Wb(i).^2)*rb*sin(theta2(i));
```

```
Ac=[Acx Acy];
```

```
Acox(i)=(dot(Ac,Roc))/(dot(Ac,Ac))*Acx(i);
```

```
Acoy(i)=(dot(Ac,Roc))/(dot(Ac,Ac))*Acy(i);
```

```
Ac_ox(i)=Acx(i)-Acox(i);
```

```
Ac_oy(i)=Acy(i)-Acoy(i);
```

```
alphaoc(i)=(abs([Ac_ox Ac_oy]))/(abs(Roc));
```

```
alphaod(i)=alphaoc(i);
```

```
%Velocidad Angular
```

```
Vcx(i)= -Wb(i)*rb*sin(theta2(i));
```

```
Vcy(i)=Wb(i)*rb*cos(theta2(i));
```

```
Vc=[Vcx Vcy];
```

```
Vcox(i)=(dot(Vc,Roc))/(dot(Vc,Vc))*Vcx(i);
```

```
Vcoy(i)=(dot(Vc,Roc))/(dot(Vc,Vc))*Vcy(i);
```

```
Vc_ox(i)=Vcx(i)-Vcox(i);
```

```
Vc_oy(i)=Vcy(i)-Vcoy(i);
```

```
Woc(i)=(abs([Vc_ox Vc_oy]))/(abs(Roc));
```

```
Wod(i)=Woc(i);
```

```
%Angulo
```

```
theta3(i+1) =-atan((h+rb*sin(theta2(i)))/(-d+rb*cos(theta2(i))));
```

```
%
```

```
%DATOS BARRA D-E y DATOS BARRA P-E
```

```
%Angulos
```

```
[theta4(i),theta5(i)] = newtonrhaptheta(rod,rde,rpe,d2,h2,theta3(i),theta40,theta50);
```

```
theta40 = theta4(i);
```

```
theta50 = theta5(i);
```

```
%Velocidad Angular
```

```
A1=[-sin(theta5(i)) -rde*sin(theta4(i)); -cos(theta5(i)) rde*cos(theta4(i))];
```

```
B1=[-Wod(i)*rod*sin(theta3(i)); -Wod(i)*rod*cos(theta3(i))];
```

```
X1=A1\B1;
```

```
Wpe(i)=X1(1);
```

```

Wde(i)=X1(2);
%Aceleracion Angular
A2=[rpe*sin(theta5(i)) rde*sin(theta4(i));rpe*cos(theta5(i)) -rde*cos(theta4(i))];
B2=[-(Wpe(i).^2)*rpe*cos(theta5(i))+alphaod(i)*rod*sin(theta3(i))+(Wod(i).^2)*rod*cos(theta3(i))];
X2=A2\B2;
alphape(i)=X2(1);
alphade(i)=X2(2);
end

```

CINETICA MECANISMO:

```

gamma=zeros(1,t_max/dt+1);
phi=zeros(1,t_max/dt+1);

for i=1:length(t)-1
    gamma(i)=(pi/2)-theta3(i);
    phi(i)= theta2(i)-gamma(i);
end

```

SISTEMA DE ECUACIONES 12x12:

$$F_{BH} + F_C \cos \gamma = m_{BC} (-\alpha_B r_{BG} \sin \theta_2 + \omega_B^2 r_{BG} \cos \theta_2) \quad (1)$$

$$-F_{BV} + F_C \sin \gamma - m_{BC} g = m_{BC} (\alpha_B r_{BG} \cos \theta_2 + \omega_B^2 r_{BG} \sin \theta_2) \quad (2)$$

$$-r_{BG} \sin \theta_2 (F_{BH} + F_C \cos \gamma) - r_{BG} \cos \theta_2 (F_{BV} + F_C \sin \gamma) - \tau_B = -\frac{1}{2} m_{BC} r_{BC}^2 \alpha_B \quad (3)$$

$$F_{DH} - F_{OH} - F_C \cos \gamma = m_{OD} (\alpha_{OD} r_{OG} \sin \theta_3 + \omega_{OD}^2 r_{OG} \cos \theta_3) \quad (4)$$

$$F_{OV} - F_{DV} - F_C \sin \gamma - m_{OD} g = m_{OD} (\alpha_{OD} r_{OG} \cos \theta_3 - \omega_{OD}^2 r_{OG} \sin \theta_3) \quad (5)$$

$$-r_{OG} \sin \theta_3 (F_{DH} + F_{OH}) + r_{OG} \cos \theta_3 (F_{DV} + F_{OV}) + (r_{OC} - r_{OG}) F_C = -\frac{1}{12} m_{OD} r_{OD}^2 \alpha_{OD} \quad (6)$$

$$F_{PH} - F_{EH} - F_{carga} = m_{PE} (\omega_{PE}^2 r_{PG} \cos \theta_5 + \alpha_{PE} r_{PG} \sin \theta_5) \quad (7)$$

$$F_{EV} - F_{PV} - m_{PE} g = m_{PE} (-\omega_{PE}^2 r_{PG} \sin \theta_5 + \alpha_{PE} r_{PG} \cos \theta_5) \quad (8)$$

$$r_{PG} \sin \theta_5 (\mathbf{F}_{EH} + \mathbf{F}_{PH} + \mathbf{F}_{carga}) - r_{PG} \cos \theta_5 (\mathbf{F}_{EV} + \mathbf{F}_{PV}) = -\frac{1}{12} m_{PE} r_{PE}^2 \alpha_{PE} \quad (9)$$

$$\mathbf{F}_{EH} + \mathbf{F}_{carga} - \mathbf{F}_{DH} =$$

$$m_{DE} (\alpha_{OD} r_{OD} \sin \theta_3 + \omega_{OD}^2 r_{OD} \cos \theta_3 - \alpha_{DE} r_{DEG} \sin \theta_4 - \omega_{DE}^2 r_{DEG} \cos \theta_4) \quad (10)$$

$$\mathbf{F}_{DV} - \mathbf{F}_{EV} - m_{PE} \mathbf{g} =$$

$$m_{DE} (\alpha_{OD} r_{OD} \cos \theta_3 - \omega_{OD}^2 r_{OD} \sin \theta_3 + \alpha_{DE} r_{DEG} \cos \theta_4 - \omega_{DE}^2 r_{DEG} \sin \theta_4) \quad (11)$$

$$-r_{DEG} \sin \theta_4 (\mathbf{F}_{EH} + \mathbf{F}_{DH} + \mathbf{F}_{carga}) - r_{DEG} \cos \theta_4 (\mathbf{F}_{EV} + \mathbf{F}_{DV}) = \frac{1}{12} m_{DE} r_{DE}^2 \alpha_{DE} \quad (12)$$

$\mathbf{F}_{BH}, \mathbf{F}_{BV}, \mathbf{F}_{OH}, \mathbf{F}_{OV}, \mathbf{F}_{DH}, \mathbf{F}_{DV}, \mathbf{F}_{PH}, \mathbf{F}_{PV}, \mathbf{F}_{EH}, \mathbf{F}_{EV}, \mathbf{F}_{carga}, \mathbf{F}_C$

%Solucion Ecuaciones

%Definir los valores necesarios

%Radios(Centro de Gravedad)

rbg=0.2;

rog=0.6;

rpg=0.5;

rdeg=0.6;

%Masas

mbc=0.5;

mod=0.4;

mpe=0.45;

mde=0.7;

%Constantes

g=9.78;

Tb=0.5;

%Definir Vectores de Fuerza

Fbh=zeros(1,t_max/dt+1);

Fbv=zeros(1,t_max/dt+1);

Foh=zeros(1,t_max/dt+1);

Fov=zeros(1,t_max/dt+1);

Fdh=zeros(1,t_max/dt+1);

Fdv=zeros(1,t_max/dt+1);

Fph=zeros(1,t_max/dt+1);

Fpv=zeros(1,t_max/dt+1);

Feh=zeros(1,t_max/dt+1);

Fev=zeros(1,t_max/dt+1);

Fcarga=zeros(1,t_max/dt+1);

```

Fc=zeros(1,t_max/dt+1);

for i=1:length(t)-1
    A3=[1 0 0 0 0 0 0 0 0 0 0 cos(gamma(i));
        0 -1 0 0 0 0 0 0 0 0 0 sin(gamma(i));
        -rbg*sin(theta2(i)) -rbg*cos(theta2(i)) 0 0 0 0 0 0 0 -rbg*sin(theta2(i))*cos(gamma(i));
        0 0 -1 0 1 0 0 0 0 0 -cos(gamma(i));
        0 0 0 1 0 -1 0 0 0 0 -sin(gamma(i));
        0 0 -rog*sin(theta3(i)) rog*cos(theta3(i)) -rog*sin(theta3(i)) rog*cos(theta3(i)) 0 0 0;
        0 0 0 0 0 0 1 0 -1 0 -1 0;
        0 0 0 0 0 0 0 -1 0 1 0 0;
        0 0 0 0 0 0 rpg*sin(theta5(i)) -rpg*cos(theta5(i)) rpg*sin(theta5(i)) -rpg*cos(theta5(i));
        0 0 0 0 -1 0 0 0 1 0 1 0;
        0 0 0 0 0 1 0 0 0 -1 0 0;
        0 0 0 0 -rdeg*sin(theta4(i)) -rdeg*cos(theta4(i)) 0 0 -rdeg*sin(theta4(i)) -rdeg*cos(theta4(i))];

    B3=[mbc*(-alhab(i)*rbg*sin(theta2(i))+(Wb(i).^2)*rbg*cos(theta2(i)));
        mbc*(alhab(i)*rbg*cos(theta2(i))+(Wb(i).^2)*rbg*sin(theta2(i)))+mbc*g;
        (-1/2)*mbc*(rbc.^2)*alhab(i)+Tb;
        mod*(alphaod(i)*rog*sin(theta3(i))+(Wod(i).^2)*rog*cos(theta3(i)));
        mod*(alphaod(i)*rog*cos(theta3(i))-(Wod(i).^2)*rog*sin(theta3(i)))+mod*g;
        (-1/12)*mod*(rod.^2)*alphaod(i);
        mpe*((Wpe(i).^2)*rpg*cos(theta5(i))+alphape(i)*rpg*sin(theta5(i)));
        mpe*(-(Wpe(i).^2)*rpg*sin(theta5(i))+alphape(i)*rpg*cos(theta5(i)))+mpe*g;
        (-1/12)*mpe*(rpe.^2)*alphape(i);
        mde*(alphaod(i)*rod*sin(theta3(i))+(Wod(i).^2)*rod*cos(theta3(i))-alphade(i)*rdeg*sin(theta4(i)));
        mde*(alphaod(i)*rod*cos(theta3(i))-(Wod(i).^2)*rod*sin(theta3(i))+alphade(i)*rdeg*cos(theta4(i)));
        (1/12)*mde*(rde.^2)*alphade(i)];

    X3=A3\B3;

    Fbh(i)=X3(1);
    Fbv(i)=X3(2);
    Foh(i)=X3(3);
    Fov(i)=X3(4);
    Fdh(i)=X3(5);
    Fdv(i)=X3(6);
    Fph(i)=X3(7);
    Fpv(i)=X3(8);
    Feh(i)=X3(9);
    Fev(i)=X3(10);
    Fcarga(i)=X3(11);
    Fc(i)=X3(12);
end

```

```

Warning: Matrix is close to singular or badly scaled. Results may be inaccurate. RCOND = 8.766744e-18.
Warning: Matrix is singular to working precision.
Warning: Matrix is close to singular or badly scaled. Results may be inaccurate. RCOND = 7.584312e-18.
Warning: Matrix is close to singular or badly scaled. Results may be inaccurate. RCOND = 5.332925e-20.
Warning: Matrix is close to singular or badly scaled. Results may be inaccurate. RCOND = 5.329301e-20.
Warning: Matrix is singular to working precision.

```


[illegible]

[illegible]

[illegible]

[illegible]

[illegible]

[illegible]

[illegible]

Warning: Matrix is singular to working precision.
Warning: Matrix is close to singular or badly scaled. Results may be inaccurate. RCOND = 1.937350e-19.
Warning: Matrix is close to singular or badly scaled. Results may be inaccurate. RCOND = 3.955665e-18.
Warning: Matrix is close to singular or badly scaled. Results may be inaccurate. RCOND = 2.900043e-18.
Warning: Matrix is close to singular or badly scaled. Results may be inaccurate. RCOND = 1.264643e-19.
Warning: Matrix is close to singular or badly scaled. Results may be inaccurate. RCOND = 2.675266e-18.
Warning: Matrix is singular to working precision.
Warning: Matrix is singular to working precision.
Warning: Matrix is singular to working precision.
Warning: Matrix is singular to working precision.
Warning: Matrix is close to singular or badly scaled. Results may be inaccurate. RCOND = 1.423879e-17.
Warning: Matrix is close to singular or badly scaled. Results may be inaccurate. RCOND = 1.093774e-18.
Warning: Matrix is close to singular or badly scaled. Results may be inaccurate. RCOND = 1.930888e-18.
Warning: Matrix is close to singular or badly scaled. Results may be inaccurate. RCOND = 4.391396e-19.
Warning: Matrix is singular to working precision.
Warning: Matrix is close to singular or badly scaled. Results may be inaccurate. RCOND = 4.549896e-19.
Warning: Matrix is close to singular or badly scaled. Results may be inaccurate. RCOND = 1.361347e-17.
Warning: Matrix is close to singular or badly scaled. Results may be inaccurate. RCOND = 1.521545e-17.
Warning: Matrix is singular to working precision.
Warning: Matrix is close to singular or badly scaled. Results may be inaccurate. RCOND = 4.455812e-19.
Warning: Matrix is close to singular or badly scaled. Results may be inaccurate. RCOND = 1.466528e-19.
Warning: Matrix is singular to working precision.
Warning: Matrix is singular to working precision.
Warning: Matrix is singular to working precision.
Warning: Matrix is close to singular or badly scaled. Results may be inaccurate. RCOND = 1.311825e-18.
Warning: Matrix is singular to working precision.
Warning: Matrix is close to singular or badly scaled. Results may be inaccurate. RCOND = 1.633373e-18.
Warning: Matrix is singular to working precision.
Warning: Matrix is singular to working precision.
Warning: Matrix is close to singular or badly scaled. Results may be inaccurate. RCOND = 8.575283e-18.
Warning: Matrix is close to singular or badly scaled. Results may be inaccurate. RCOND = 5.095499e-20.
Warning: Matrix is close to singular or badly scaled. Results may be inaccurate. RCOND = 4.918819e-19.
Warning: Matrix is singular to working precision.