

We first set up the same set of basic assumptions and variables.

```
GRAV <- 9.8 # gravity (m/s^2)
MASS <- 3.11*10^(-5) # mass (kg)
I_CM <- 1/12 # rotational inertia (kg m^2)
PHI <- pi/6 # angle of Ft relative to floor (parallel) (rad)
L <- 0.5 # distance from the center of mass (of rotation point) to tension (m)
FT <- 12 # tension force (N)
OMEGA <- 0.1 # angle of line orthogonal to floor relative to gravity (rad) (because shifted axis)
```

Additionally, we set the time interval and seed values for all values that's tallied:

```
dt <- 0.0001
t_max <- 5

vx <- 0
vy <- 0

x <- 0
y <- 0

time <- 0
theta <- 0
thetadot <- 0
```

Great. Let's start writing the loop now by setting up a bunch of arrays and writing their values in.

```
cTime = NULL
cTorqueNet = NULL
cDDTheta = NULL
cDTheta = NULL
cTheta = NULL

cAccelX = NULL
cAccelY = NULL
cVelX = NULL
cVelY = NULL
cPosX = NULL
cPosY = NULL

cFNetX = NULL
cFNetY = NULL

cKERot = NULL
cKETrans = NULL
```

Awesome, we will start tallying, then!

```
for (i in 0:(t_max/dt)) {
  # write down standard values
  cTime[i] = time
  cTheta[i] = theta
```

```
# torque is calculated via the dot product between the vector of the radius projected out
# and also the angle at which the thing is at (so like theta + phi)
#
# note that, unlike the tabled version, L here represets distance from CoM to tension
# application
torque <- FT*L*cos(theta+PHI)
cTorqueNet[i] = torque

# from knowing the torque, we could divide out the rotational inertia to figure the
# acceleration of rotation
thetadotdot <- torque/I_CM
cDDTheta[i] <- thetadotdot

# from this, we could of course tally for the velocity of theta as well
thetadot <- dt*thetadotdot + thetadot
cDTheta[i] <- thetadot

# After knowing the value for theta, we could use it to calculate the net forces in
# both components.
# we define up as +, down as -, right as +, left as -
fnet_x <- FT*sin(PHI) + MASS*GRAV*sin(OMEGA)
fnet_y <- FT*cos(PHI) - MASS*GRAV*cos(OMEGA)
# "I think ax and ay will be constant with time" --- Mark

cFNetX[i] = fnet_x
cFNetY[i] = fnet_y

# Dividing the mass out, we could get accelerations
ax <- fnet_x/MASS
ay <- fnet_y/MASS

# We also tally the components seperately for velocity
vx <- ax*dt + vx
vy <- ay*dt + vy

# We finally tally the positions as well
x <- vx*dt + x
y <- vy*dt + y

# And we add them together to tally
cAccelX[i] = ax
cAccelY[i] = ay

cVelX[i] = ax
cVelY[i] = ay

cPosX[i] = x
cPosY[i] = y

cKERot[i] = 0.5 * I_CM * thetadot^2
cKETrans[i] = 0.5 * MASS * (vx^2+vy^2)

# We increment the time and theta based on the tallying variable
time <- dt + time
```

```

    theta <- dt*thetadot + theta
  }

rotating_link <- data.frame(cTime,
  cTheta,
  cDTheta,
  cDDTheta,
  cTorqueNet,
  cAccelX,
  cAccelY,
  cVelX,
  cVelY,
  cPosX,
  cPosY,
  cKERot,
  cKETrans)

names(rotating_link) <- c("time",
  "theta",
  "d.theta",
  "dd.theta",
  "net.torque",
  "accel.x",
  "accel.y",
  "vel.x",
  "vel.y",
  "pos.x",
  "pos.y",
  "ke.rot",
  "ke.trans")

```

Let's import some visualization tools, etc.

```
library(tidyverse)
```

Let's first see the head of this table:

```
head(rotating_link)
```

1e-04	6.23538290724796e-07	0.0124707635697569	62.353806625089	5.19615055209075	6.97836748313892	0.64126402568861	6.97836748313892	0.64126402568861	2.09351024494167e-07	1.92379207706583e-08	6.47999766719895e-06	9.82176645607458e-07	2e-04	1.87061464770048e-06	0.0187061397427812	62.3537617302432	5.1961468108536	6.97836748313892	0.64126402568861	6.97836748313892	0.64126402568861	4.18702048988335e-07	3.84758415413166e-08	1.45799860031857e-05	2.20989745261678e-06	3e-04	3.7412286219786e-06	0.0249415091815625	62.3536943878128	5.1961411989844	6.97836748313892	0.64126402568861	6.97836748313892	0.64126402568861	6.97836748313892e-07	6.4126402568861e-08	2.59199533439152e-05	3.92870658242983e-06	4e-04	6.23537954013485e-06	0.0311768696413229	62.353604597604	5.196133716467	6.97836748313892	0.64126402568861	6.97836748313892	0.64126402568861	1.04675512247084e-06	9.61896038532915e-08	4.04998833596683e-05	6.13860403504662e-06	5e-04	9.35306650426713e-06	0.0374122188772587	62.3534923593581	5.19612436327984	6.97836748313892	0.64126402568861	6.97836748313892	0.64126402568861	1.46545717145917e-06	1.34665445394608e-07	5.83197550549962e-05	8.83958981046713e-06
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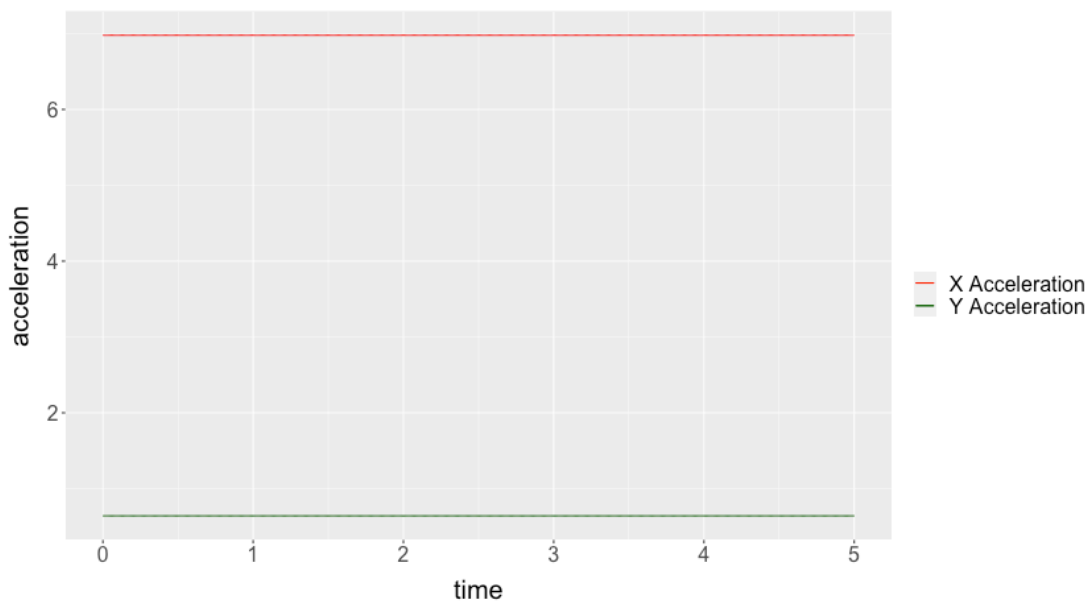
```
6e-04 1.3094288391993e-05 0.0436475546445339 62.3533576727519 5.19611313939599 6.97836748313892
0.64126402568861 6.97836748313892 0.64126402568861 1.9539428952789e-06 1.79553927192811e-07
7.93795427686487e-05 1.20316639086914e-05
```

Before we start graphing, let's set a common graph theme.

```
default.theme <- theme(text = element_text(size=20), axis.title.y = element_text(margin = margin(t = 0,
```

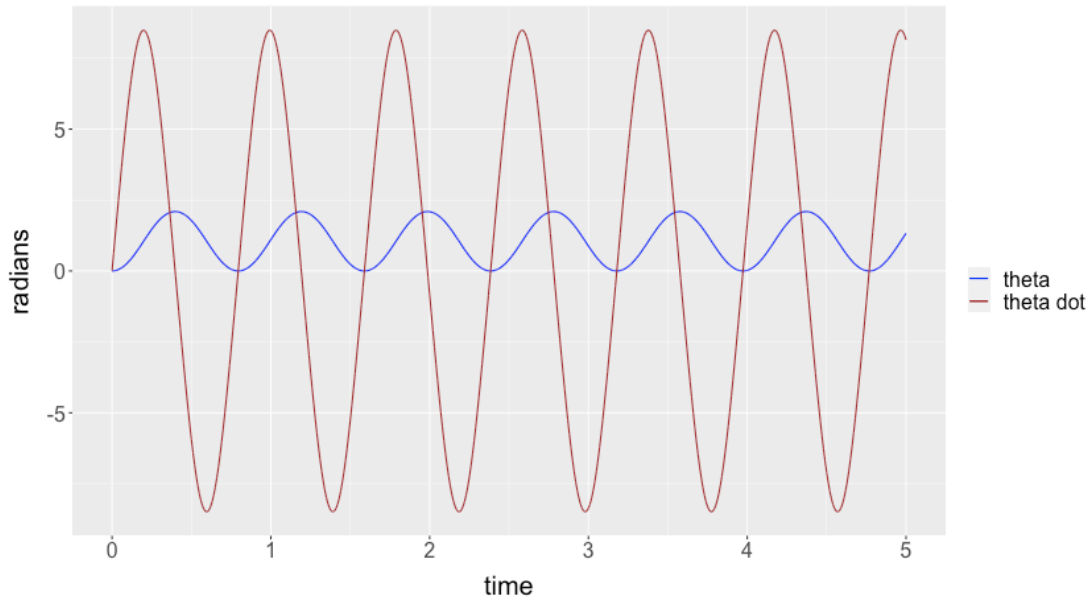
We will graph a_x and a_y on top of each other:

```
rotating_link %>% ggplot() + geom_line(aes(x=time, y=accel.x, colour="X Acceleration")) + geom_line(aes
```



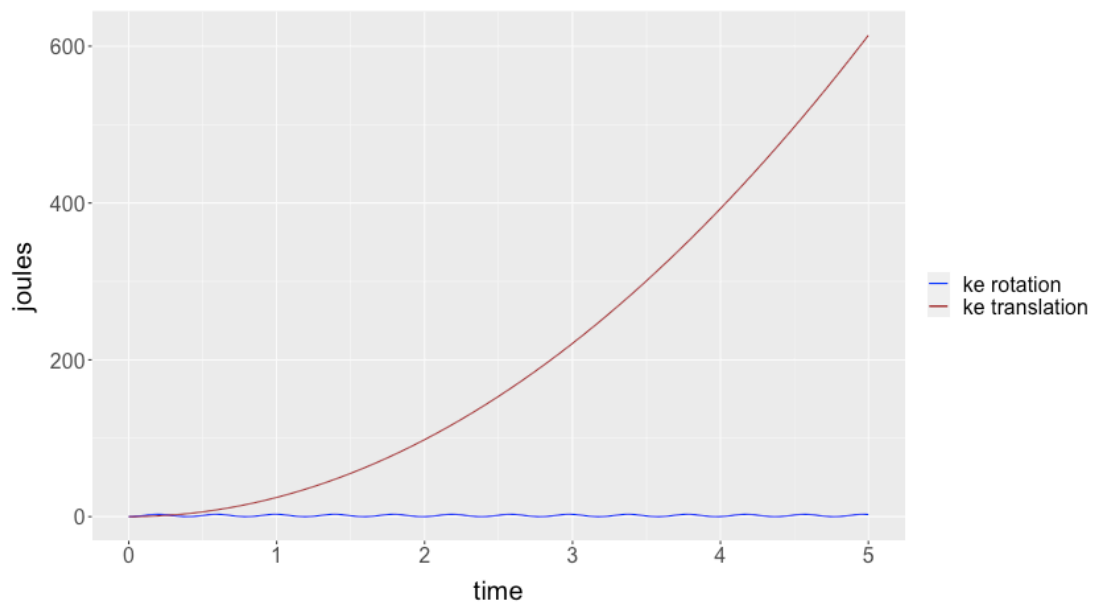
Theta dot atop theta:

```
rotating_link %>% ggplot() + geom_line(aes(x=time, y=theta, colour="theta")) + geom_line(aes(x=time, y=
```



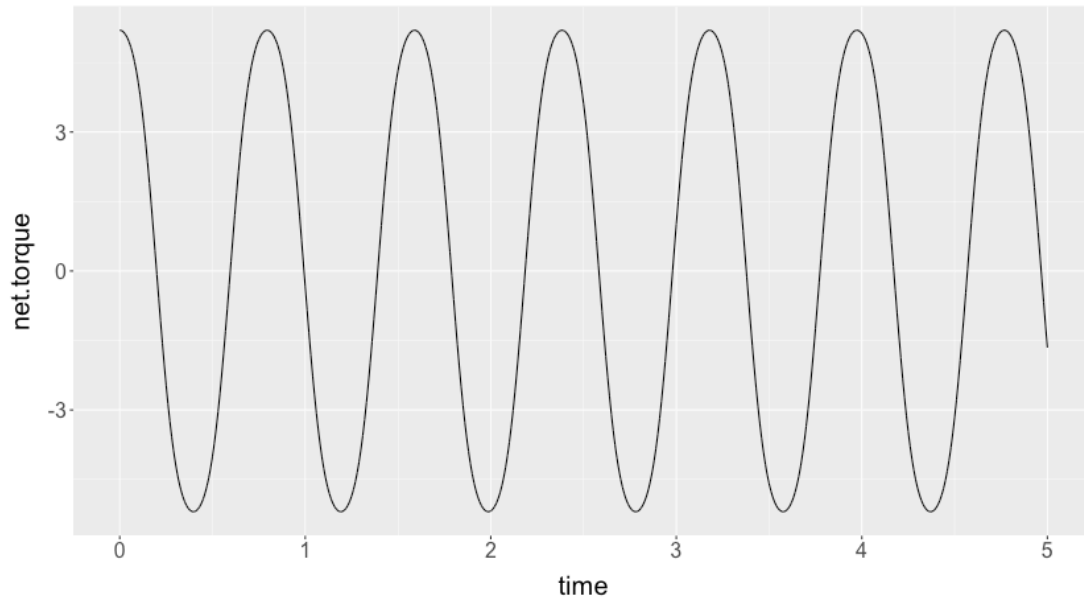
We finally, plot KE rotation and translation

```
rotating_link %>% ggplot() + geom_line(aes(x=time, y=ke.rot, colour="ke rotation")) + geom_line(aes(x=t
```



Let's also plot torque as well.

```
rotating_link %>% ggplot() + geom_line(aes(x=time, y=net.torque)) + default.theme
```



Finally, let's plot velocity and position

```
rotating_link %>% ggplot() + geom_line(aes(x=time, y=pos.x, colour="x position")) + geom_line(aes(x=time, y=pos.y, colour="y position"))
```

