

Lab 5 Pre-Lab

- Find the natural frequencies and mode shapes of a linear, time-invariant mechanical system with

$$M = \begin{pmatrix} 3 & 0 \\ 0 & 3/4 \end{pmatrix}, K = \begin{pmatrix} 4 & -3 \\ -3 & 5 \end{pmatrix}.$$

$$\therefore 0 = \det(K - M \cdot \omega^2) = \frac{9}{4} \omega^4 - 18 \omega^2 + 11 = \left(\frac{3}{2} \omega^2 - 11\right) \left(\frac{3}{2} \omega^2 - 1\right)$$

$$\therefore \omega_1 = \sqrt{\frac{22}{3}}, \omega_2 = \sqrt{\frac{2}{3}} \quad \begin{aligned} (K - M \omega_1^2) \begin{pmatrix} A_1 \\ A_2 \end{pmatrix} &= 0 \Rightarrow 6A_1 = -A_2 \\ (K - M \omega_2^2) \begin{pmatrix} B_1 \\ B_2 \end{pmatrix} &= 0 \Rightarrow B_1 = \frac{3}{2} B_2 \end{aligned}$$

- Suppose that an undamped, linear, time-invariant, two-degree-of-freedom mechanical system has a mode shape

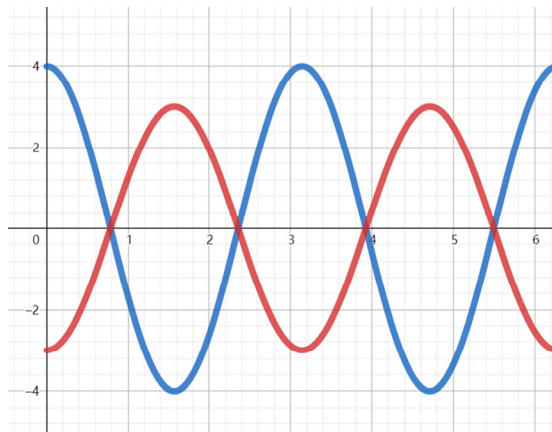
$$\begin{pmatrix} 4 \\ -3 \end{pmatrix}$$

with corresponding natural frequency 2. Sketch the steady-state response for the two degrees of freedom if the inputs $f_1(t)$ and $f_2(t)$ are both harmonic with frequency 1.98 and there is small damping present.

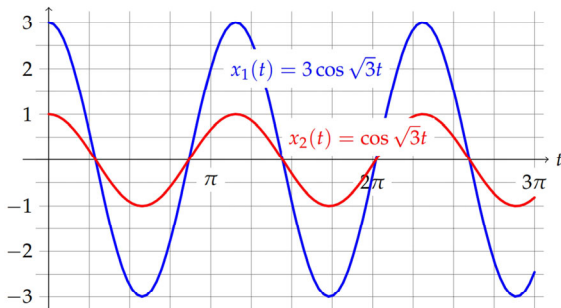
$$f = 1.98$$

$$x_1(t) = 4 \cos(2t)$$

$$x_2(t) = -3 \cos(2t)$$



- Consider a linear, time-invariant, two-degree-of-freedom mechanical system that has two natural frequencies whose ratio is not a rational number. Suppose that a combination of impulses $f_1(t)$ and $f_2(t)$ results in the response shown in the graph below. Use this to determine one of the natural frequencies and the corresponding mode shape.

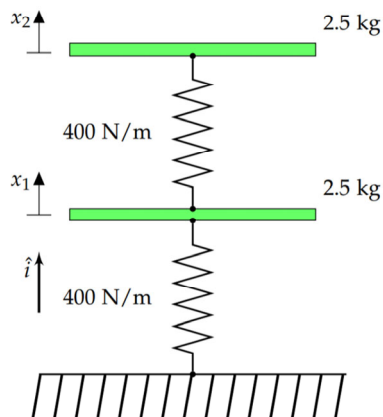


$\therefore x_1(t)$ and $x_2(t)$ are harmonic

\therefore They must be free response

From the graph we know $\omega = \sqrt{3}$ column matrix is $\begin{pmatrix} 3 \\ 1 \end{pmatrix}$
phase difference is π

4. Consider the two-degree-of-freedom mechanical suspension, and upper plate, respectively, relative to the undeformed configuration of the two springs.



Compute the natural frequencies and the corresponding mode shapes.

$$M \begin{pmatrix} \ddot{x}_1(t) \\ \ddot{x}_2(t) \end{pmatrix} + K \begin{pmatrix} x_1(t) \\ x_2(t) \end{pmatrix} = \begin{pmatrix} 0 \\ 0 \end{pmatrix}$$

$$M = \begin{pmatrix} m_1 & 0 \\ 0 & m_2 \end{pmatrix}, \quad K = \begin{pmatrix} k_1 + k_2 & -k_2 \\ -k_2 & k_2 \end{pmatrix}$$

$$\omega^2 = \frac{m_1 k_2 + m_2 k_1 + m_2 k_2 \pm \sqrt{(m_1 k_2 + m_2 k_1 + m_2 k_2)^2 - 4 m_1 m_2 k_1 k_2}}{2 m_1 m_2}$$

$$\therefore \omega_1 = 20.467, \quad \omega_2 = 7.8175$$