

# Recitation 12

Wednesday 14<sup>th</sup> January, 2015

## Week 12 : Class Exercises

### Exercise 3

1

$$\begin{aligned}mg &= kx_0 \\ \therefore x_0 &= \frac{mg}{k}\end{aligned}$$

2

Let the distance about the equilibrium position be

$$\begin{aligned}z &= x - x_0 \\ \therefore \ddot{z} &= \ddot{x}\end{aligned}$$

Therefore,

$$\begin{aligned}\ddot{z} + \frac{k}{m}z &= 0 \\ \therefore z(t) &= A \cos \frac{k}{m}t + B \sin \frac{k}{m}t\end{aligned}$$

According to the initial conditions,

$$z(t) = -\frac{mv_0}{k} \sin \frac{k}{m}t$$

## Week 12 : Home Assignment

### Exercise 5

$$-kx - f = m\ddot{x}$$

Considering torques about the centre,

$$Rf = \frac{mR^2}{2}\ddot{\theta}$$

As the cylinder is purely rolling,

$$\dot{x} = \dot{\theta}R$$

$$\ddot{x} = \ddot{\theta}R$$

Therefore,

$$\begin{aligned} f &= \frac{m\ddot{x}}{2} \\ \therefore -kx + \frac{m\ddot{x}}{2} &= m\ddot{x} \\ \therefore \ddot{x} + \frac{2k}{3m}x &= 0 \\ \therefore \omega &= \sqrt{\frac{2k}{3m}} \end{aligned}$$

Also, as the cylinder is purely rolling, mechanical energy is conserved.

Therefore,

$$\begin{aligned} E &= \frac{1}{2}kx^2 + \frac{1}{2}m\dot{x}^2 + \frac{1}{2}I\dot{\theta}^2 \\ &= \frac{1}{2}kx^2 + \frac{1}{2}m\dot{x}^2 + \frac{1}{4}m\dot{x}^2 \\ \therefore 0 &= kx\dot{x} + m\dot{x}\ddot{x} + \frac{1}{2}m\dot{x}\ddot{x} \\ \therefore 0 &= \ddot{x} + \frac{2k}{3m}x \\ \therefore \omega &= \sqrt{\frac{2k}{3m}} \end{aligned}$$

## Week 13 : Class Exercises

### Exercise 1

$$\begin{aligned}v_{m,M} &= a\dot{\theta}\hat{\theta} \\ &= a\dot{\theta}(\cos\theta\hat{i} + \sin\theta\hat{j}) \\ &= a\omega(\cos\theta\hat{i} + \sin\theta\hat{j})\end{aligned}$$

By COLM in the horizontal direction,

$$\begin{aligned}0 &= m(v_m)_x + M(v_M)_x \\ \therefore (v_m)_x &= -\frac{M}{m}(v_M)_x \\ (v_{m,M})_x &= (v_m)_x - (v_M)_x \\ &= -\left(\frac{M}{m} + 1\right)(v_M)_x \\ \therefore -(v_M)_x \left(\frac{M+m}{m}\right) &= a\dot{\theta}\cos\theta\hat{i} \\ \therefore (v_M)_x &= -a\dot{\theta}\cos\theta\hat{i} \left(\frac{m}{M+m}\right) \\ \therefore (v_m)_x &= -\frac{M}{m} \cdot -a\dot{\theta}\cos\theta\hat{i} \left(\frac{m}{M+m}\right) \\ &= \left(\frac{M}{M+m}\right)a\dot{\theta}\cos\theta\hat{i}\end{aligned}$$

$$(v_m)_y = a\dot{\theta}\sin\theta\hat{j}$$

Therefore,

$$\begin{aligned}v_m &= \left(\frac{M}{M+m}\right)a\dot{\theta}\cos\theta\hat{i} + a\dot{\theta}\sin\theta\hat{j} \\ v_M &= -\left(\frac{m}{M+m}\right)a\dot{\theta}\cos\theta\hat{i}\end{aligned}$$