

Recap

In the last lecture, we introduced the two Euler's axioms for relating the translational and rotational motion of an RB to the causal forces and moments, respectively.

There exists an inertial frame I such that Euler's axioms hold true which leads to the governing eqn of motion of an RB:

$$\boxed{1} \quad \dot{\underline{P}}|_I = \underline{F}_{\text{net}}^{\text{ext}} = m \underline{v}_{c/I} \quad (\text{Recall } \underline{P}_{IF} = m \underline{v}_{P/F})$$

$$\boxed{2} \quad \dot{\underline{H}}_{0/I} = \underline{M}_{\text{net}}^{\text{ext}}$$

6 scalar equations



a) Necessary and sufficient for solving motion of an RB

\Rightarrow (3 translation + 3 rotation \equiv 6 degrees of freedom)

b) NOT sufficient to solve for the motion of a deformable body

For applying Euler's axioms to an RB (or a system of RBs), it is necessary that

a) the RB (or the system) be sketched in isolation from its surroundings, and

b) the external forces and moments exerted by the surroundings on the RB (or the system) be drawn on it

Such a diagram is called FREE BODY DIAGRAM (FBD)

Note that the forces exerted by one part of the RB (or system) on another part of the RB (or system) are called internal forces

These internal forces should not be shown in an FBD since they do not appear in Euler's axioms.

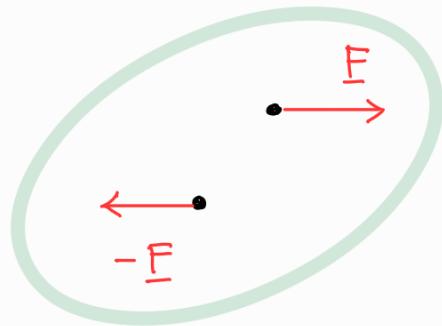
To apply Euler's axioms to a system, we need to compute forces (\underline{F}) and moments (\underline{M}_o) due to the external loads acting on it.

We shall call a load system consisting of forces and moments simply as a force system

In this lecture, we will learn how to replace a given system of forces by a simpler equivalent system.

An important concept associated with the effect of a force on an RB is the moment of a force about a point and abt an axis. We will also recap couple caused by two parallel forces with same magnitude but opposite direction. As you will see that we can replace any system of forces acting on an RB by an equivalent system consisting of one force acting on an RB and one couple!

Recap of Couple:



Two equal and opposite forces acting along different (parallel) lines of action

→ Couple can have only a turning (rotating) effect

→ Couple stays the same about any point in space



FREE VECTOR! \Leftrightarrow No change on shifting the location!

→ Representation of couple:



Directed double

lined arrow

Curled

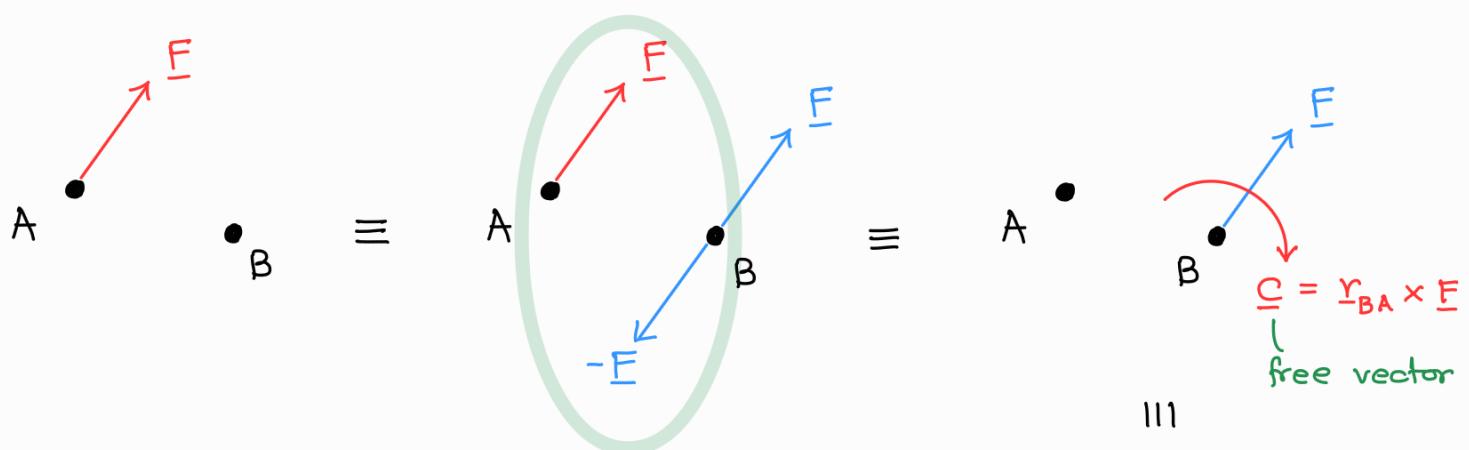
arrow

length: Magnitude of C

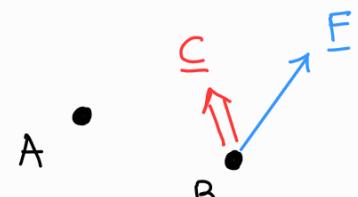
Direction of C given by
right-hand-thumb rule

direction: Direction of C

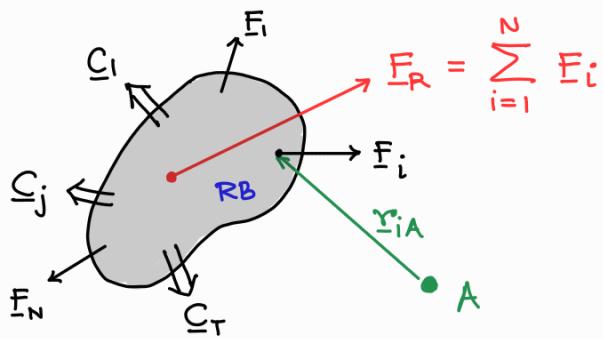
What happens when F is shifted from a pt A to another pt B? It generates a couple as well!



Force $\xrightarrow[\text{when shifted to another pt}]{} \begin{bmatrix} \text{Same Force} \\ \text{One couple} \end{bmatrix}$

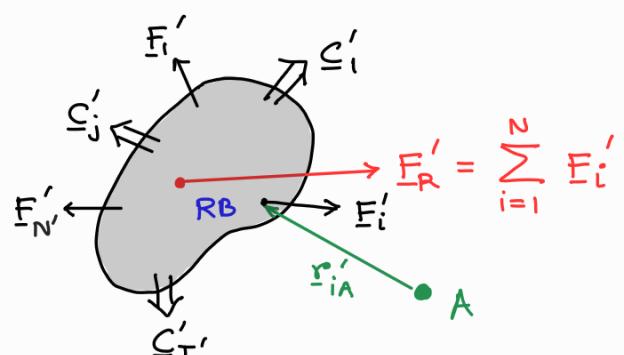


Equivalent Force Systems



Force System 1

F_i and C_j are part of
Force system 1



Force System 2

F'_i and C'_j are part of
Force system 2

Note, in general $\left\{ \begin{array}{l} F_i \neq F'_i \\ C_j \neq C'_j \\ r_{iA} \neq r'_{iA} \end{array} \right.$

(N need not be equal to N')
(T need not be equal to T')

The force systems 1 and 2 are said to be equivalent if both the force systems result in the same net force and same net moment about a point 'A' → could be anywhere in space

$$\underline{F}_R = \underline{F}'_R \Rightarrow \sum_{i=1}^N \underline{F}_i = \sum_{i=1}^{N'} \underline{F}'_i \quad \text{--- (a)}$$

\Leftrightarrow AND

$$\underline{M}_A = \underline{M}'_A \Rightarrow \underbrace{\sum_{i=1}^N \underline{r}_{iA} \times \underline{F}_i + \sum_{j=1}^T \underline{C}_j}_{{\underline{M}}_A} = \underbrace{\sum_{i=1}^{N'} \underline{r}'_{iA} \times \underline{F}'_i + \sum_{j=1}^{T'} \underline{C}'_j}_{{\underline{M}}'_A} \quad \text{--- (b)}$$

Equivalent force systems result in same motion of an RB.

If conditions (a) and (b) have been found true for one point A in space, it follows that (b) will hold true for every other point (say 'B')

Moment abt pt B due to force system 1

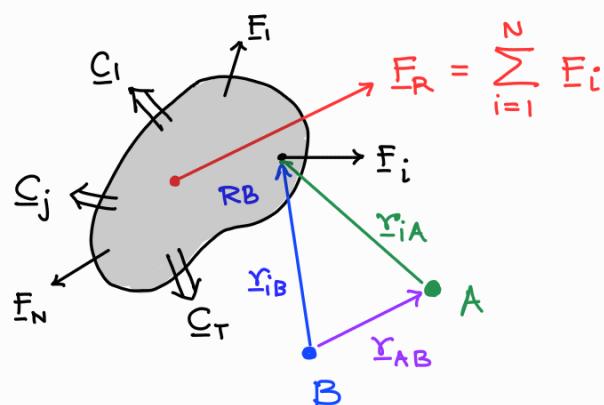
$$\underline{M}_B = \sum_{i=1}^N \underline{r}_{iB} \times \underline{F}_i + \sum_{j=1}^T \underline{C}_j$$

$$= \sum_{i=1}^N (\underline{r}_{AB} + \underline{r}_{iA}) \times \underline{F}_i + \sum_{j=1}^T \underline{C}_j$$

$$= \underbrace{\sum_{i=1}^N \underline{r}_{iA} \times \underline{F}_i + \sum_{j=1}^T \underline{C}_j}_{\underline{M}_A} + \sum_{i=1}^N \underline{r}_{AB} \times \underline{F}_i$$

Same for all i

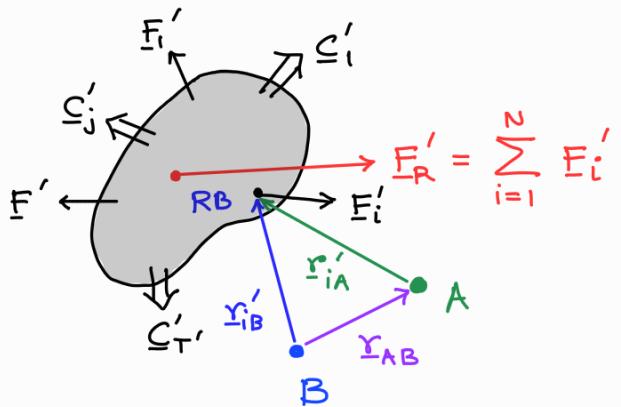
$$= \underline{M}_A + \underline{r}_{AB} \times \left(\sum_{i=1}^N \underline{F}_i \right) \quad \Rightarrow \quad \underline{M}_B = \underline{M}_A + \underline{r}_{AB} \times \underline{F}_R \quad \text{--- (x)}$$



Similarly, for force system 2

$$\underline{M}_B' = \underline{M}_A' + (\underline{\tau}_{AB} \times \underline{F}_R')$$

Since $\underline{M}_A = \underline{M}_A'$ and $\underline{F}_R = \underline{F}_R'$



Therefore, the moment sum of two equivalent force systems is the same about ANY point

Thus if $\underline{F}_R = \underline{F}_R'$ AND $\underline{M}_A = \underline{M}_A'$,

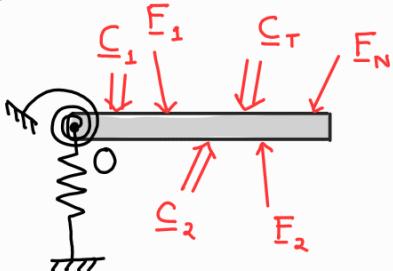
$$\Rightarrow \underline{M}_B = \underline{M}_B' \text{ or } \underline{M}_C = \underline{M}_C', \text{ etc.}$$

where A, B, C are any points in space.

Note: $\underline{M}_A \neq \underline{M}_B \neq \underline{M}_C$ in general

In addition to application of Euler's axioms, the motivation for studying equivalent force systems comes from several practical applications

Example

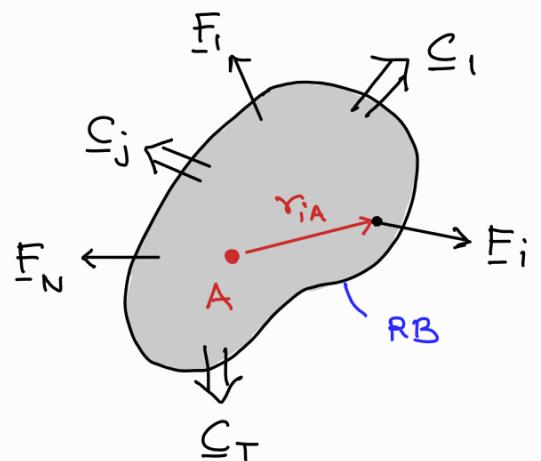


For design purposes, we may need to find the resultant effect of all the forces & couples at the support O to calculate the spring stiffnesses for resisting the forces and moments.

This is one of the motivations to study equivalent force systems.

Now, since any two equivalent force system will result into identical motion of an RB, we can replace a given force system (N forces, T couples) by an equivalent system with just one force (\underline{F}_R) acting at a point A on RB along with a couple ($\underline{\underline{C}}_R$)_A

$$\left. \begin{array}{l} \text{Forces : } \underline{F}_i \quad i = 1, 2, \dots, N \\ \text{Couples : } \underline{\underline{C}}_j \quad j = 1, 2, \dots, T \end{array} \right\} \begin{array}{l} \text{Original} \\ \text{forces} \\ \& \text{couples} \\ \text{acting} \\ \text{on RB} \end{array}$$



'A' → point where we want to shift
the forces and couples

① Couple \Rightarrow free vector \Rightarrow No change on shifting
↳ same at any point in space

② Force $\xrightarrow{\text{on shifting}}$ [Same force] + [a couple]

What is the RESULTANT equivalent force & couple at A?

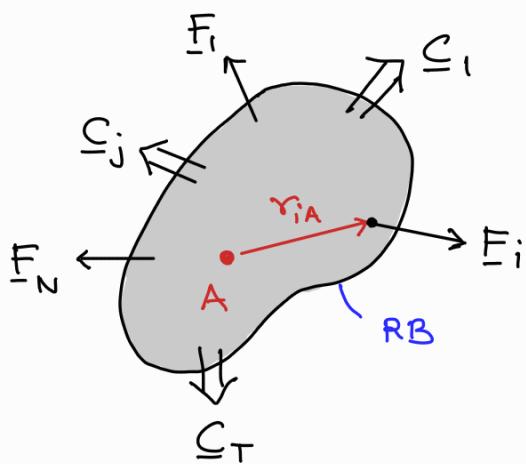
$$\left. \begin{array}{l} \text{Resultant} \\ \text{force} \\ \text{system} \\ \text{at A} \end{array} \right\} \begin{array}{l} \text{Net force } (\underline{F}_R) = \sum_{i=1}^N \underline{F}_i \\ \text{Net couple } (\underline{\underline{C}}_R) = \sum_{j=1}^T \underline{\underline{C}}_j + \sum_{i=1}^N \underline{r}_{iA} \times \underline{F}_i \end{array}$$

(subscript R is for resultant)

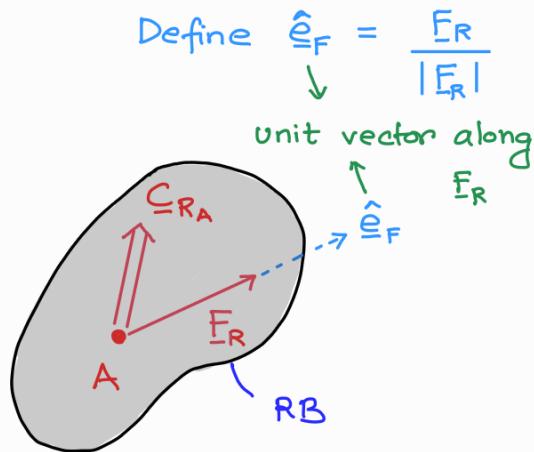
Original couples

Couple contribution due to shifting of force \underline{F}_i from pt 'i' to point 'A'

Any force system can be reduced to a single resultant force \underline{F}_R and a single resultant couple \underline{C}_{RA} at point A



\equiv



Furthermore,

\underline{C}_{RA} can be resolved into components parallel to \underline{F}_R and perpendicular to \underline{F}_R

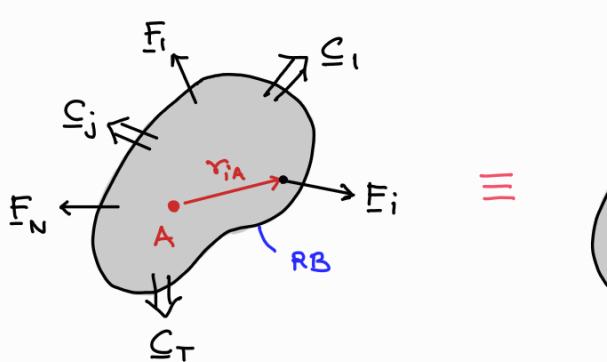
$$\Rightarrow \underline{C}_{RA} = \underline{C}_{RA}^{\parallel} + \underline{C}_{RA}^{\perp}$$

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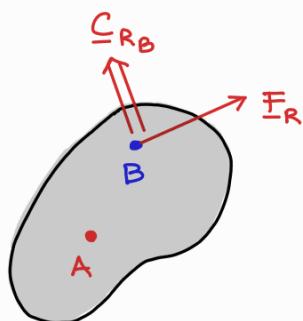
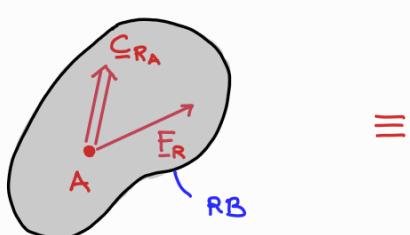
$$\underline{C}_{RA}^{\parallel} = (\underline{C}_{RA} \cdot \hat{e}_F) \hat{e}_F \quad \text{and} \quad \underline{C}_{RA}^{\perp} = \underline{C}_{RA} - \underline{C}_{RA}^{\parallel}$$

Now, what is the couple at a different point B?

Recall: $\underline{C}_{RB} = \underline{C}_{RA} + (\underline{r}_{BA} \times \underline{F}_R)$



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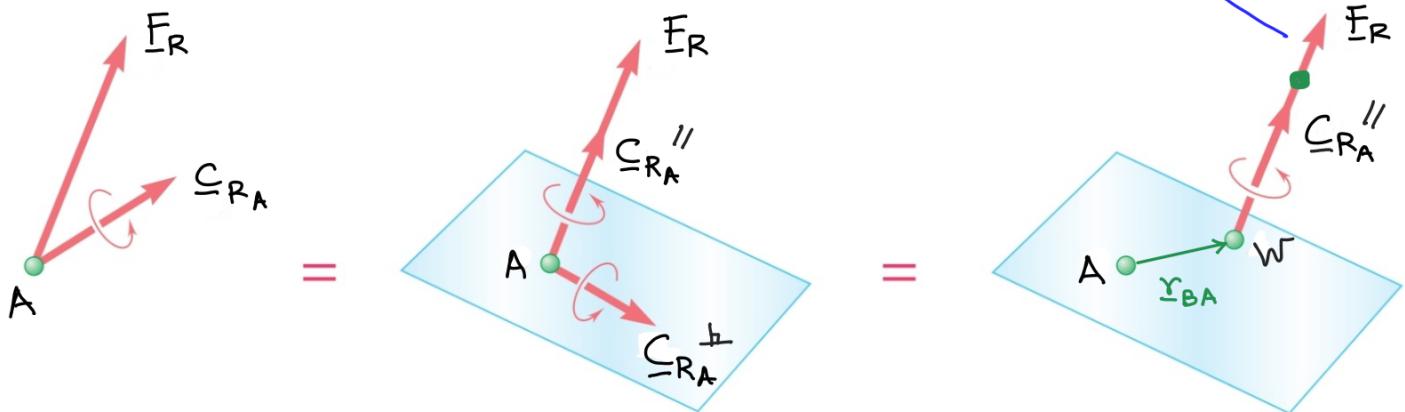


$$\underline{C}_{RB} = \underline{C}_{RA} + (\underline{r}_{BA} \times \underline{F}_R)$$

$$= \underline{C}_{RA}'' + \underline{C}_{RA}^{\perp} + \underbrace{\underline{r}_{BA} \times \underline{F}_R}_{\text{A point 'W' can be chosen s.t.}}$$

$$\text{Constraint} \rightarrow \underline{C}_{RA}^{\perp} + \underline{r}_{WA} \times \underline{F}_R = \underline{0}$$

The equivalent force system at point W is called "**WRENCH**"



NOTE: The choice of pt W is not arbitrary. The pt W must satisfy

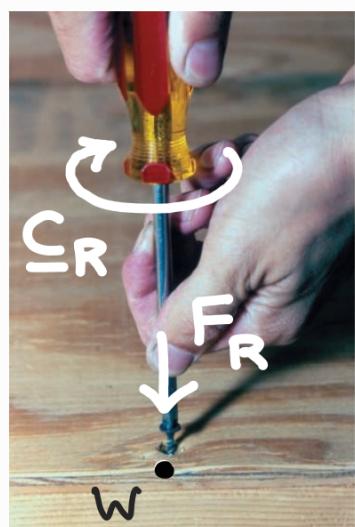
$$(\underline{F}_R)_A = (\underline{F}_R)_W \quad \& \quad \underline{C}_{RA}^{\perp} + \underline{r}_{WA} \times \underline{F}_R = \underline{0}$$

WRENCH



A force system where the net resultant of force and moment have the same direction!

e.g. force system of a screw driver



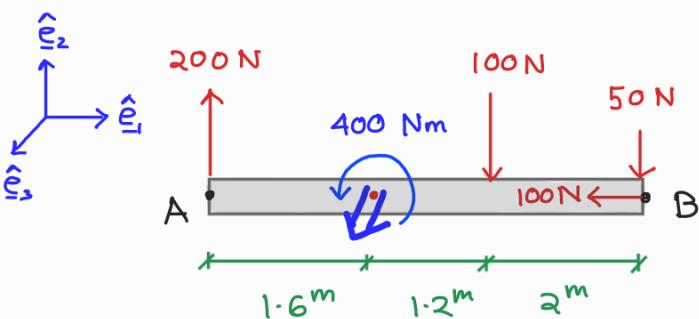
For a general 3D force system,
simplest resultant is a WRENCH

For some special cases the simplest resultant force system can simply be just one force (E_R) placed at a special point OR a single couple C_{RA} only (if $E_R = 0$)

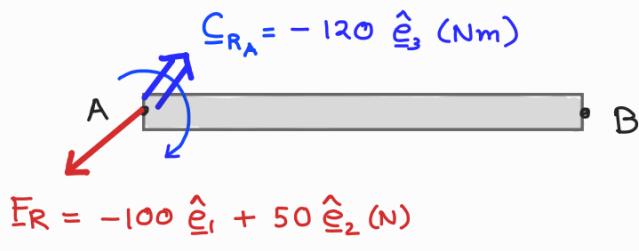
- (1) Co-planar force systems }
 (2) Parallel force systems } special cases

(1) Coplanar Force Systems

All forces are in one plane, and couples (if any) are normal to the plane of action of forces



equivalent III



Suppose

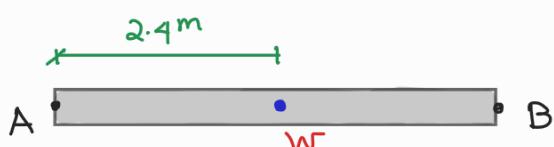
- a) all forces are in $\hat{e}_1 - \hat{e}_2$ plane
- b) all couples are along \hat{e}_3 only

$$C_{RA} = C_{RAz} \hat{e}_3$$

$$\Rightarrow C_{RA} // = 0$$

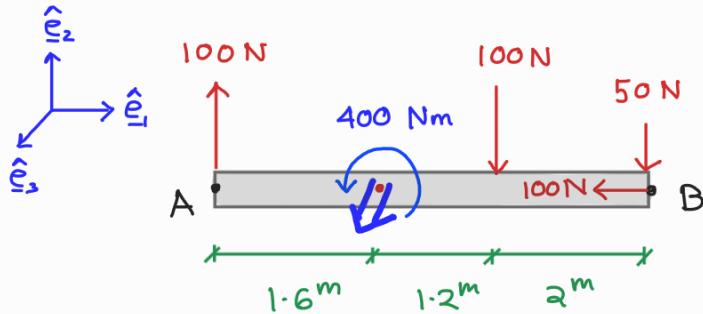
Simplest resultant (wrench)

equivalent WRENCH



has E_R only
(just one force)

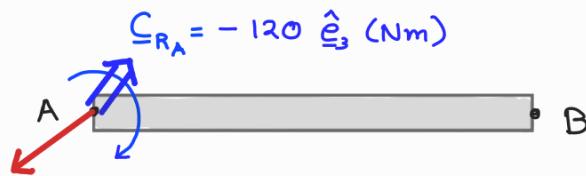
$$E_R = -100 \hat{e}_1 - 50 \hat{e}_2$$



Calculation steps

$$\underline{F}_R = -100 \hat{e}_1 + (100 - 100 - 50) \hat{e}_2 \\ = -100 \hat{e}_1 - 50 \hat{e}_2 \text{ (N)}$$

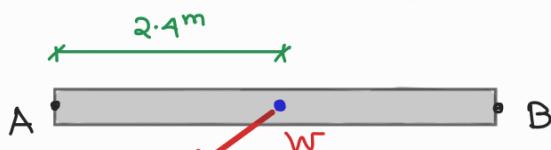
equivalent III



$$\underline{F}_R = -100 \hat{e}_1 - 50 \hat{e}_2 \text{ (N)}$$

equivalent III
WRENCH

Resultant force
sys. at W



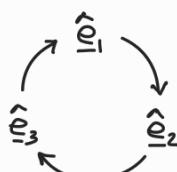
$$\underline{F}_R = -100 \hat{e}_1 - 50 \hat{e}_2 \text{ (N)}$$

$$\underline{C}_{RA} = \text{Resultant couple at pt A} \\ = [(100)(0) + (-100)(1.6+1.2) \\ + (-50)(1.6+1.2+2) \\ + 400] \hat{e}_3 + (-100)(0) \hat{e}_3 \\ = -120 \hat{e}_3 \text{ (Nm)}$$

Note: $\underline{C}_{RB} \neq \underline{C}_{RA}$

Wrench location:

$$\Sigma_{WA} \times \underline{F}_R = \underline{C}_{RA} \\ \Rightarrow (r_1 \hat{e}_1 + r_2 \hat{e}_2) \times \\ (-100 \hat{e}_1 - 50 \hat{e}_2) = -120 \hat{e}_3 \\ \Rightarrow \underbrace{-50 r_1 + 100 r_2}_{\text{Equation of wrench line}} = -120$$

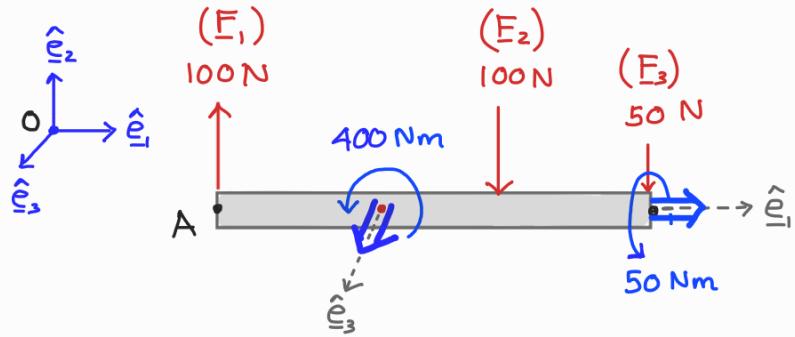


If $r_2 = 0$, then $r_1 = \frac{120}{50} = 2.4 \text{ m}$

(2) Parallel Force Systems

It comprises of forces which are all acting parallel to one line and couples (if any) have components only perpendicular to that line

Ex: all forces are (say) parallel to \hat{e}_2 line, and couples present are



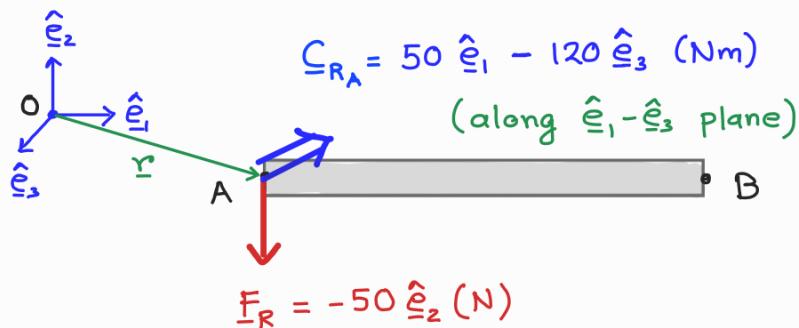
along \hat{e}_1 and/or \hat{e}_3

magnitude

$$F_i = F_{iy} \hat{e}_2$$

$$C_i = C_{ix} \hat{e}_1 + C_{iz} \hat{e}_3$$

equivalent III



$$F_R = F_{Ry} \hat{e}_2$$

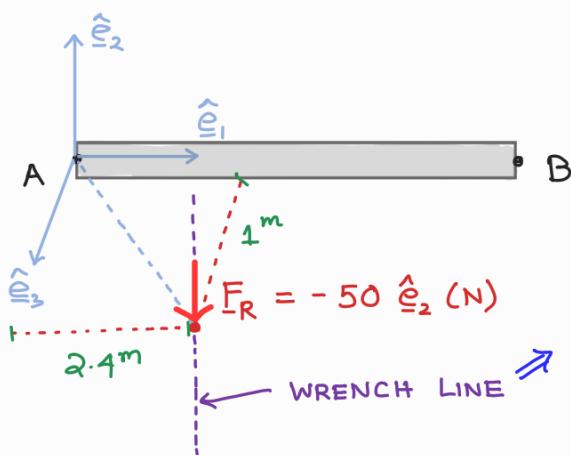
and

$$C_{RA} = C_{Rx} \hat{e}_1 + C_{Rz} \hat{e}_3$$

Since $\underline{r} \times F_R$ is \perp to F_R

equivalent III
WRENCH

$$\Rightarrow C_{RA}'' = 0$$



Application of resultant force F_R

anywhere on this line would lead to a WRENCH system