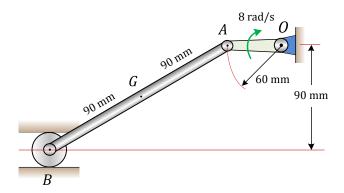
# MMAN2300 Engineering Mechanics 2 Part B: Rigid Body Dynamics Problem solving session – 2 WEEK 8\_S2\_2018

#### **Question 1:**

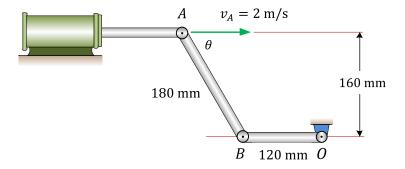
When crank OA passes the horizontal position as shown below, determine the velocity of the centre G of link AB using the method of instant centres.



 $[v_G = 0.277 \text{ m/s}]$ 

## **Question 2:**

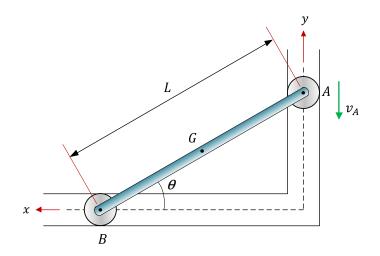
Horizontal motion of the piston rod of the hydraulic cylinder controls the rotation of link OB about O. For the instant shown,  $v_A = 2$  m/s and OB is horizontal. Use the method of instant centres to solve for the angular velocity of OB.



 $[\omega_{OB} = 8.58 \, \text{rad/s CCW}]$ 

### **Questions 3-4:**

The rigid link AB is 221 mm long and has a roller at each end. The rollers are constrained to move in the guides. The end A has a constant velocity of 7.6 m/s in the direction shown, and at this instant  $\theta = 27.4^{\circ}$ . Find the angular velocity of link AB and the velocity of roller B at this instant.

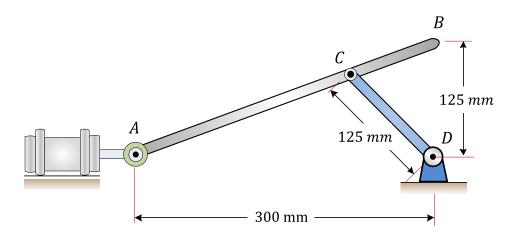


$$[\omega_{AB} = 38.735 \text{ rad/s CW}; v_B = 3.940 \text{ m/s} -]$$

#### **Questions 5-7:**

Movement of the solenoid plunger shown below gives pin A of the mechanism a velocity of 125 mm/s horizontally to the right for some short interval of its motion. For this instant, determine:

- (a) the angular velocity  $\omega_{AB}$  using the method of instant centres,
- (b) the angular velocity  $\omega_{CD}$ ,
- (c) the velocity  $v_B$  of pin B.



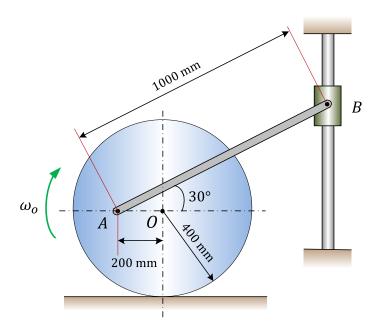
[
$$\omega_{AB} = 0.42 \text{ rad/s CCW}$$
;  $\omega_{CD} = 1.0 \text{ rad/s CW}$ ;  $v_B = 145.34 \text{ m/s}$ ]

# **Questions 8-9:**

The wheel in figure shown, rolls without slipping with the constant clockwise angular velocity  $\omega_0 = 2$  rad/s.

- (a) Calculate the angular velocity of bar AB.
- (b) Calculate the velocity of the slider *B* when the mechanism is in the position shown.

Use the instant centre method, and an analytical solution is required.



[
$$\omega_{AB} = 1.6 \text{ rad/s CCW}$$
;  $v_B = 1.79 \text{ m/s}$