# Dynamics of mass, spring and damper system

Dinesh A(153010009)

Saturday 22$^{\text{nd}}$ October, 2016

## 1 Introduction

To study a motion of a mass with given initial state connected to a wall with a spring and a damper can be done using differential equations. Lets assume a mass (m) is connected to a wall with spring of stiffness k and a damper of constant c. Assume that the mass m is given a initial displacement of x and released with zero velocity

### 1.1 Forces on mass

Since the mass attached to a spring and a damper, there will be two forces on the mass when it is disturbed from its equilibrium position.

#### 1.1.1 Hooke's law

Hooke's law states that if a spring is elongated with an amount x, then force exerted by the spring on the object elongating is

$$F_s = -kx \tag{1}$$

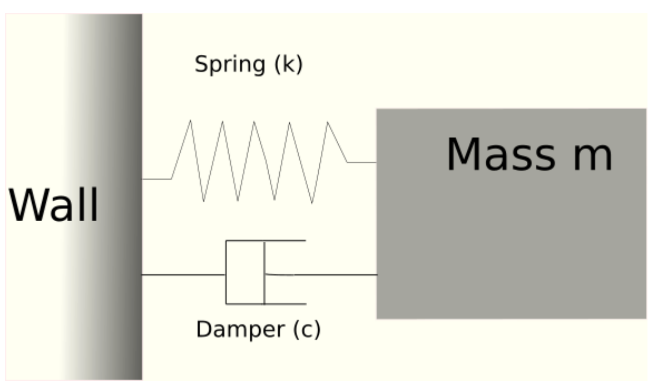


Figure 1: Mass spring damper system

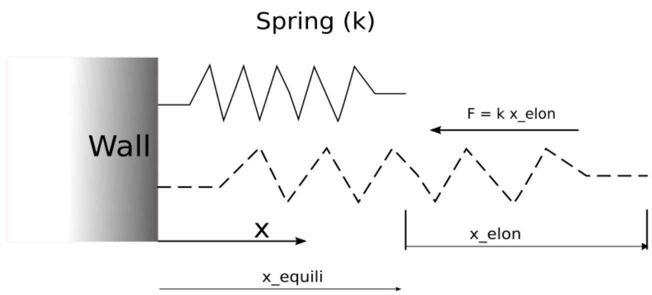


Figure 2: Force by an elongated spring

#### 1.1.2 Damping force

The force from the damper to reduce the energy of the mass is

$$F_d = -c\frac{dx}{dt} \tag{2}$$

The total force on the mass neglecting gravity at a given time is

$$F_{total} = F_s + F_d \tag{3}$$

## 2 Applying Newton's second law

From Newton's second law the equation of motion[2] can be written as

$$m\frac{d^2x}{dt^2} = F_{total} \tag{4}$$

This second order differential equation can be decoupled into two first order differential equations and velocity and position can be calculated using a scipy integrator for time t.

$$\frac{dx}{dt} = v \tag{5}$$

$$\frac{d^2x}{dt^2} = v = F_{total}/m \tag{6}$$

## 3 Results

Using the following python code the velocity and position can be plotted against the time t.

```
import numpy as np
from scipy.integrate import odeint
```

```
import matplotlib.pyplot as plt


def mass_spring_damp_acc(state_of_system, time):
    """Right hand side of scipy.odeint, At each time step return
    the velocity and acceleration to evaluate the position.

    :param state_of_system: [position and velocity] as an array
    :param time: time
    :returns: [velocity and acceleration]
    :rtype: list

    """
    pos = state_of_system[0]
    vel = state_of_system[1]
    # Constants of mass damper
    spring_constant = 2.5
    damping_constant = 0.2
    mass = 1.5

    # compute the acceleration
    acc = (-spring_constant * pos - damping_constant * vel) / mass
    return [vel, acc]

    # plt.legend(loc='upper right')


INITIAL_STATE = [3.0, 0.0]
TIME = np.arange(0, 30, 0.1)
ALL_STATES = odeint(mass_spring_damp_acc, INITIAL_STATE, TIME)
plt.plot(TIME, ALL_STATES[:, 0], label='position')
plt.plot(TIME, ALL_STATES[:, 1], label='velocity')
plt.xlabel('Time')
plt.ylabel('Position and Velocity')
plt.title('Mass damper system position and velocity with time')
plt.annotate(
    'Position',
    xy=(0, 3),
    xytext=(3, 1.5),
    arrowprops=dict(
        facecolor='black', shrink=0.05))
plt.annotate(
    'Velocity',
    xy=(0, 0),
    xytext=(7, 1.5),
    arrowprops=dict(
```

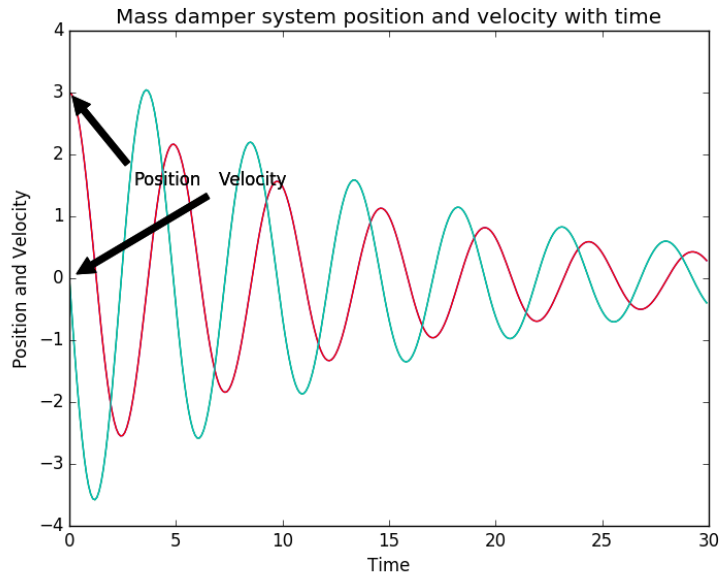


Figure 3: Position and velocity of mass damper spring system with time

```
        facecolor='black', shrink=0.05))
plt.savefig('result.png')
```

## References


[1] Jacob Pieter Den Hartog. *Mechanical vibrations*. Courier Corporation, 1985.

[2] Singiresu S Rao and Fook Fah Yap. *Mechanical vibrations*, volume 4. Addison-Wesley New York, 1995.