

SYDE 351 Project Report

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Abstract

This report analyzed the behaviour of a dynamic system using bond graph modeling and MATLAB simulation. The system consists of two rotating connected wheels that exhibit slip due to the springs between them. The modeling of the system was split into several stages to account for slip and the position of the mass was treated as the output of the system. Modeled results were very similar to actual results and it was observed that much of the movement was sinusoidal in nature. The final result is an imperfect oscillation that is a combination of two oscillations and the relative geometries of the two wheels.

I. INTRODUCTION

A simple prototype was chosen to be built, taking inspiration from the chain mechanism of bicycles. The prototype¹, seen in Figure 1, is composed of two wheels of varying sizes. Physically, the user rotates the top wheel which in turn rotates the bottom wheel. The bottom wheel slips suddenly every rotation due to the elastics that connect both wheels.

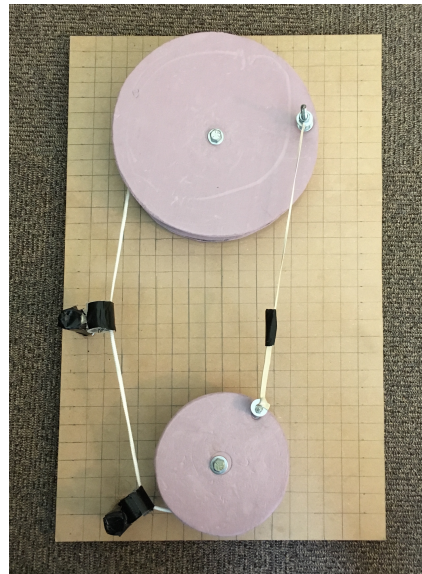
II. PROTOTYPE

The two rotating wheels are connected through two pathways. Firstly, an inextensible rope which acts as a transformer transfers the angular velocity of the big wheel to the smaller. Secondly, both wheels have fixtures near their edges which are attached to elastics. The two elastics, which vary in length and strength, are connected together with a small mass in the middle. The prototype features mechanical rotation (turning wheels) and translation (moving mass). The wheels are made out of foam and the mass in the middle is a thin screw wrapped in duct tape. A schematic diagram of the prototype can be seen in Figure 2.

The user drives the prototype by rotating the handle of the larger wheel. Both wheels rotate

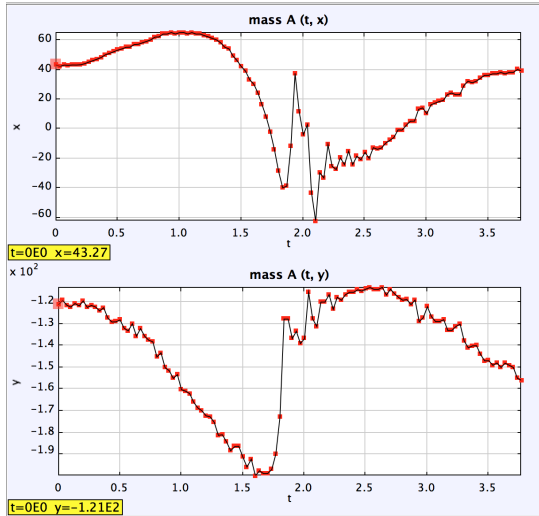
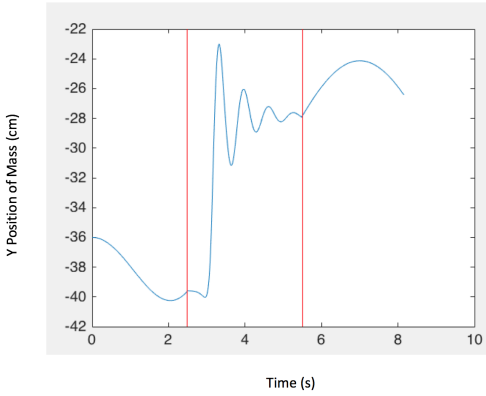
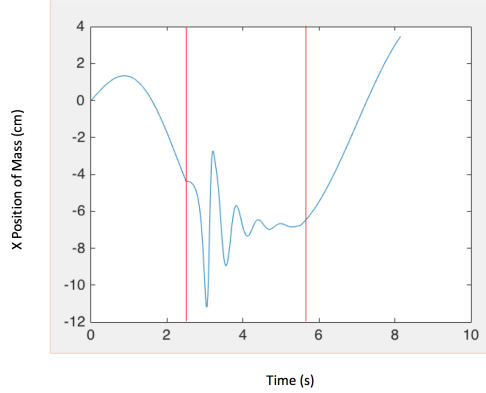
¹Video of the prototype in action can be seen here: youtu.be/hUUK9l1cf5w

Figure 1: Photograph of the prototype



smoothly initially, until the elastic gets stretched far enough to contract rapidly, causing the bottom wheel to slip. When the bottom wheel slips, the rope gains a lot of slack that would often get tangled around the axle. This problem was addressed by adding two guide rails that constrain the rope from tangling. The prototype has to be rewound before every use.

Figure 4: Simulation (top) vs. Testing (bottom)



(x_3, x_4) , the momentum of the mass between them (p_5) and the angular momentum of the bottom wheel (L_2). The values chosen for each of the parameters in the system are shown in Table 1.

Table 1: Parameter values chosen

| Parameter | Value |
|-----------|----------------------------|
| k_3 | 20 N/m |
| k_4 | 30 N/m |
| m_5 | 0.5 kg |
| J_2 | 25 kg · m ² |
| R | 125 kg · m ² /s |
| b_6 | 1.5 kg/s |

In the first and last stage, all the springs and masses were in static equilibrium at every moment, meaning that the two wheels spun at constant angular velocities and the mass would move according to the applicable geometry. During the slip however, the movement of the bottom wheel due to the applied moment resulted in the bottom spring contracting, creating a disequilibrium. This in turn moves the mass and causes it to oscillate.

V. DISCUSSION

By comparing the two plots created from the simulation to the ones created from tracking the motion of the mass through software, it can be seen that they are very similar. Firstly, both stages 1 and 3 have similar sinusoidal movements, though the ones from the real model are less smooth and have more chaotic wobbles. This is mostly because of the inconsistency in the source of flow that is the hand moving the top wheel. Moreover, it can be seen that the amplitudes and relative phases of the sinusoidal waves are different. This is because of the inaccurate measurement of the geometries of the wheels. Although measuring the radii of the wheels is trivial, they are not constant as the winding of the rope changes the dimensions of the wheels.

Looking at stage 2 the plots are also very similar, though the oscillation in the simulation is again much smoother and even than the one in the real model. This is mostly because the elastics are not perfectly linear springs and thus do not act like they are modeled in the simulation. However, the oscillations die down at approximately the same rate, meaning the damping was chosen fairly accurately.