Lagrangian Dynamics Project

Rigid-Body Spring Pendulum

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By:

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Dr. Mark Sensmeier
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ES204 Dynamics – Fall 2018

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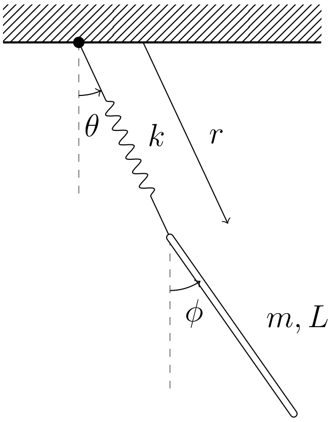
1 Conceptualize the Problem



The pendulum system consists of a rigid bar pinned to the free end of a linear spring, which rotates about its opposite end at a fixed point; there are three degrees of freedom, since the spring and bar each have an individual angular deflection with respect to the vertical, and the radial distance the bar is from the point of rotation due to the variation in the length of the spring.

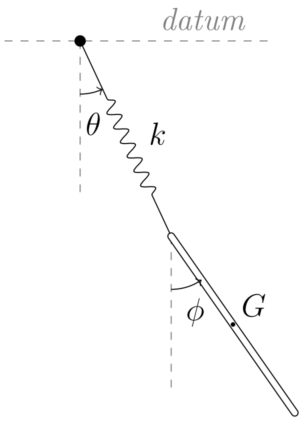
1.1 Constants and Assumptions

Constants:		Assumptions:
Bar Mass:	$m = 1$ kg	No Losses
Bar Length:	$L = 1$ m	Released from Rest
Gravity:	$g = 9.81 ^m/_{s^2}$	Uniform Slender Bar
Linear Spring:		Planar
Spring Coefficient:	$k = 25\ ^N/_m$	Rigid-Body Dynamics
Unstretched Length:	$L = 0.5$ m	

We are asked to determine the following:

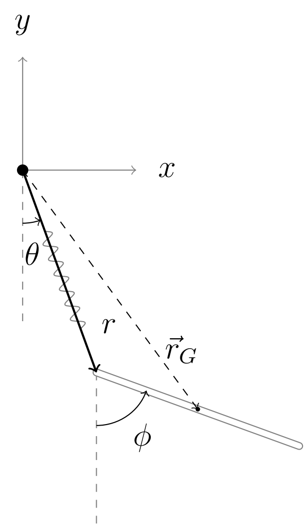
1. The Equations of Motion for the system via the Lagrangian method.
2. Integrate the Equations of Motion using various initial conditions and plot the behavior of the system for 10 seconds.
   (a) $\theta_o = 0\ rad$, $\phi_o = 0\ rad$
   (b) $\theta_o = ^\pi/_{18}\ rad$, $\phi_o = ^\pi/_9\ rad$
   (c) $\theta_o = ^\pi/_6\ rad$, $\phi_o = ^\pi/_3\ rad$
3. Plot the total energy versus time for all 3 cases.
4. Repeat 2. and 3. using a '`RelTol`' of 1e-6 and '`AbsTol`' of 1e-9 for the `ode45` integration tolerances.

2 Free Body Diagram



G: Center of gravity of the bar

3 Coordinate Frame



4 Sum of Forces

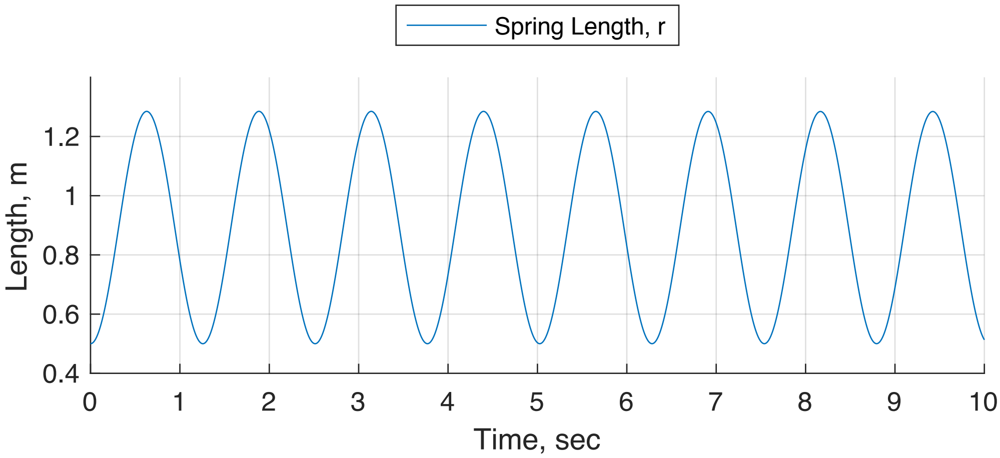
5 Constraints

The system is fully constrained, therefore no constraint equations were needed to solve the problem.

6 Solve for the Equations of Motion

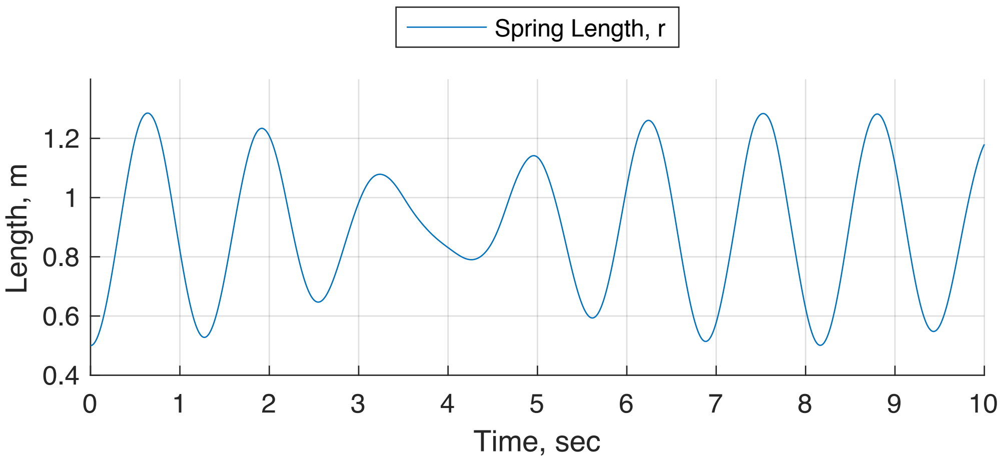
7 Solve the Equations of Motion

Figure 1: Numerical Solution Motion Behavior Plot, (θ_o : 0, ϕ_o : 0)



(a) Spring Length vs. Time

Figure 2: Numerical Solution Motion Behavior Plots, (θ_o : $\pi/18$, ϕ_o : $\pi/9$)

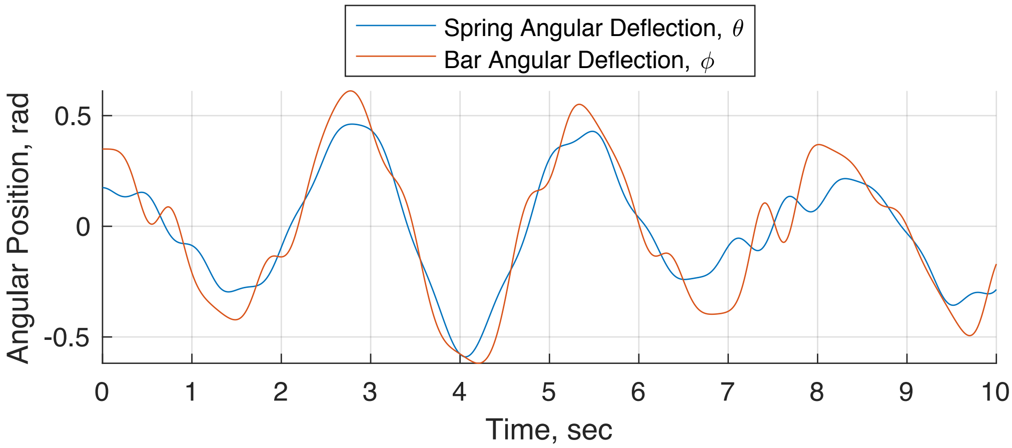


(a) Spring Length vs. Time

8 Does it Make Sense?

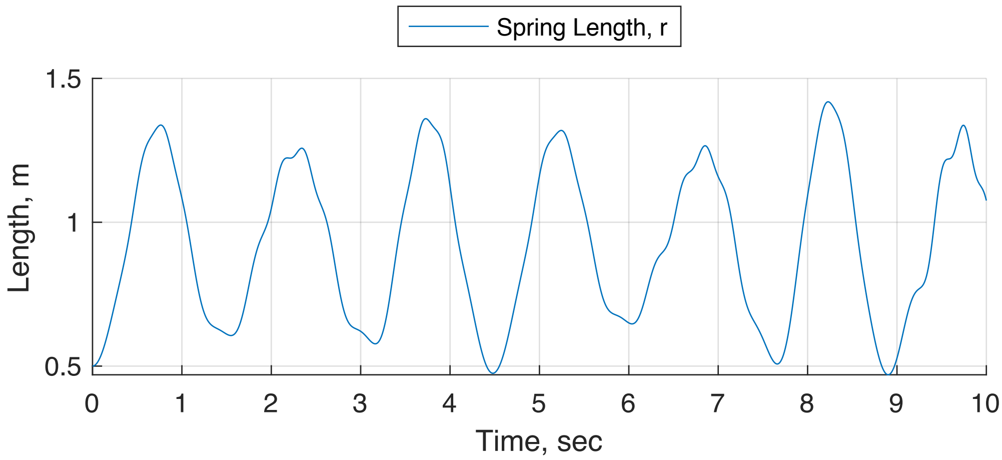
8.1 Units

Checking with the MATLAB symbolic units tool (from Section 9.3):

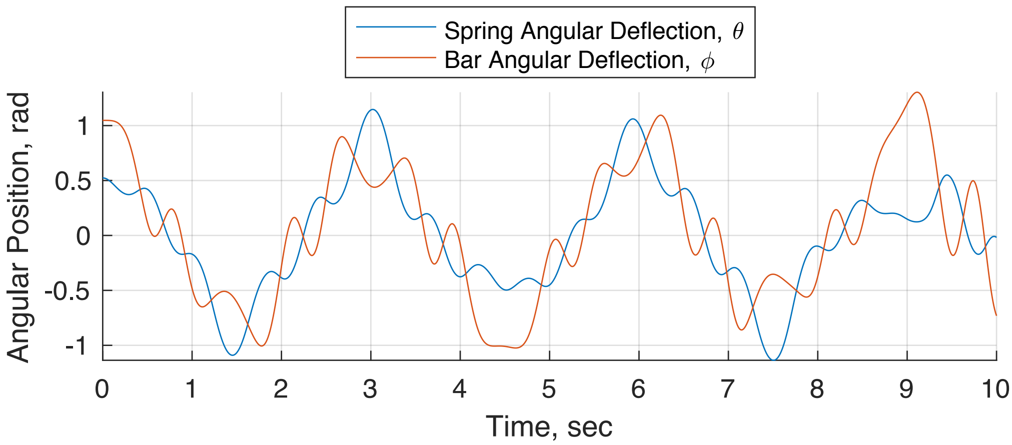


(b) Angular Position vs. Time

Figure 3: Numerical Solution Motion Behavior Plots, ($\theta_o : {}^{\pi}/_{6},\ \phi_o : {}^{\pi}/_{3}$)



(a) Spring Length vs. Time



(b) Angular Position vs. Time

8.2 Magnitude

9 Appendix

9.1 Attributions

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Joint Effort

9.2 Analytical Solution

9.3 Numerical Solution