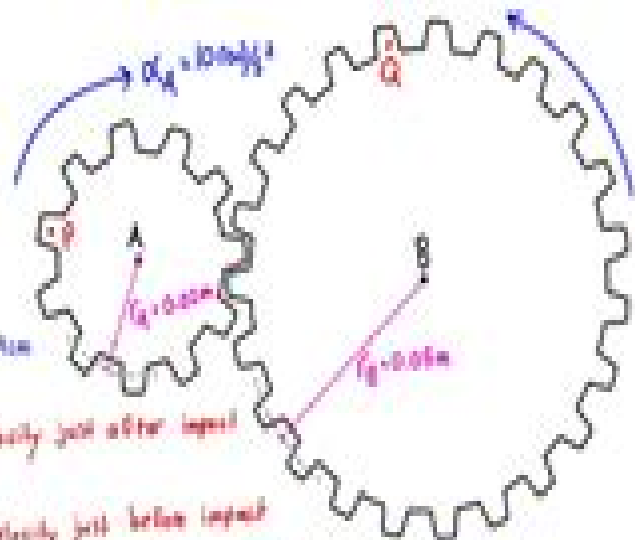
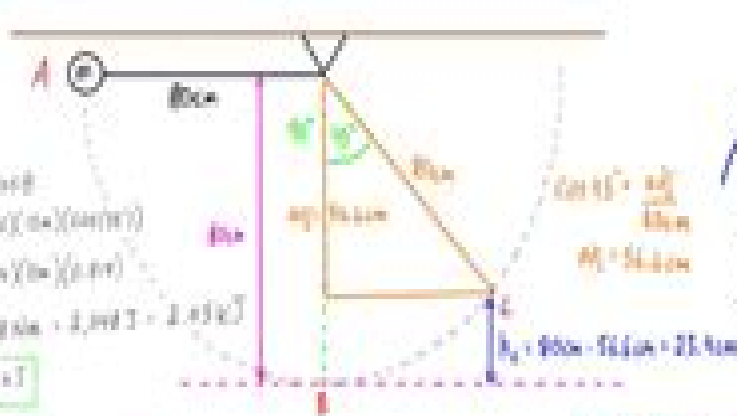




$$\begin{aligned}
 m &= 1048 \text{ kg} \\
 v_i &= 0 \\
 v_f &= 100 \text{ km/h} \\
 t &= 37 \text{ s} \\
 P_{avg} &=?
 \end{aligned}$$

$$\begin{aligned}
 U &= F \cdot d \cos \theta \\
 U &= (3500 \text{ N}) \cdot (100 \text{ m}) \cos(0^\circ) \\
 U &= (3500 \text{ N}) \cdot (100 \text{ m}) \cdot (1) \\
 U &= 3.5 \times 10^5 \text{ J} \\
 U &= 3.5 \times 10^5 \text{ J}
 \end{aligned}$$



$$e = \frac{v_{B1} - v_{A1}}{v_{A1} - v_{B1}}$$

relative velocity just after impact

relative velocity just before impact

Write conservation of momentum in x direction

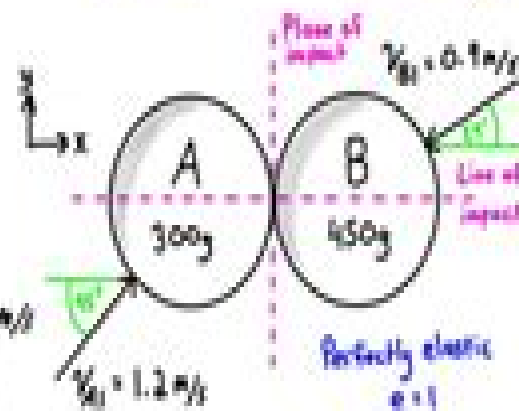
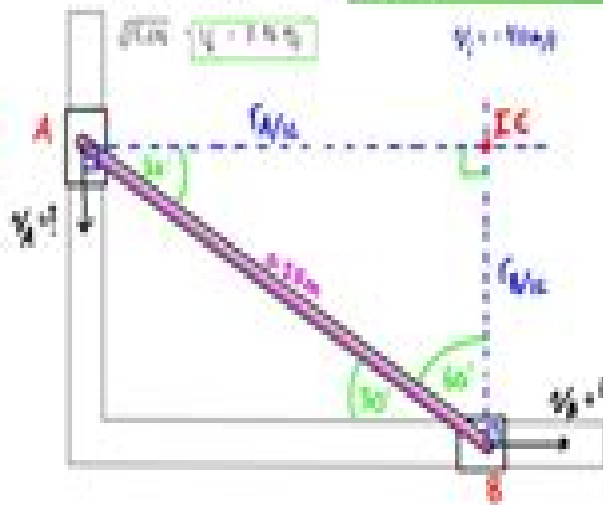
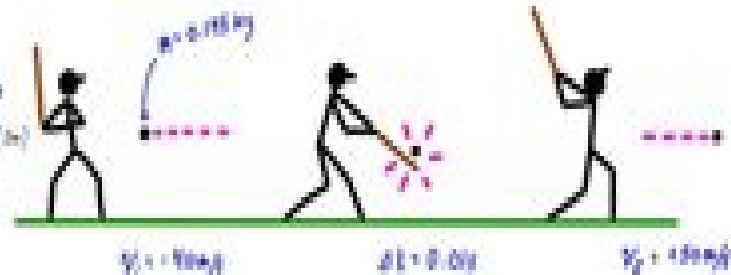
Momentum before = Momentum after

$$m_A v_{Ax1} + m_B v_{Bx1} = m_A v_{Ax2} + m_B v_{Bx2}$$

$$\begin{aligned}
 (0.3 \text{ kg})(0.449 \text{ m/s}) + (0.45 \text{ kg})(0.449 \text{ m/s}) &= (0.3 \text{ kg})v_{Ax2} + (0.45 \text{ kg})v_{Bx2} \\
 0.2547 \text{ kg} \cdot \text{m/s} + 0.20205 \text{ kg} \cdot \text{m/s} &= 0.3 \text{ kg} v_{Ax2} + 0.45 \text{ kg} v_{Bx2} \\
 0.45675 \text{ kg} \cdot \text{m/s} &= 0.3 \text{ kg} v_{Ax2} + 0.45 \text{ kg} v_{Bx2} \\
 0.45675 \text{ m/s} &= 0.3 v_{Ax2} + 0.45 v_{Bx2} \quad (1)
 \end{aligned}$$

Notice that 0.45675 is the "momentum before"

$$\begin{aligned}
 T_1 + U_1 &= T_2 + U_2 \\
 \frac{1}{2}mv_1^2 + mgh_1 &= \frac{1}{2}mv_2^2 + mgh_2 \\
 \frac{1}{2}(100 \text{ kg})(10 \text{ m/s})^2 + (100 \text{ kg})(10 \text{ m}) &= \frac{1}{2}(100 \text{ kg})v_2^2 + (100 \text{ kg})(10 \text{ m}) \\
 10000 \text{ J} + 1000 \text{ J} &= 50v_2^2 + 1000 \text{ J} \\
 11000 \text{ J} &= 50v_2^2 + 1000 \text{ J} \\
 10000 \text{ J} &= 50v_2^2 \\
 200 &= v_2^2 \\
 v_2 &= 14 \text{ m/s}
 \end{aligned}$$



$$T_i + \sum U_{1-2} = T_f$$

Initial kinetic energy

Final kinetic energy

The work done

$$T_1 = \frac{1}{2}mv_1^2$$

$$T_2 = \frac{1}{2}mv_2^2$$

$$\sum U_{1-2} = F_s \cos \theta$$

Force of friction

No because friction opposes the motion

Engineering Dynamics

Keith D. Hjelmstad



Engineering Dynamics:

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O'Reilly, 2019-02-23 This primer is intended to provide the theoretical background for the standard undergraduate mechanical engineering course in dynamics Representative problems are discussed and simulated throughout the book to illustrate fundamental concepts and explore the development of mathematical models for mechanical systems The text grew out of the author's desire to provide a complement to traditional texts on the subject and promote a systematic approach to problem solving For all the examples discussed in the primer a systematic four step approach is employed The third edition of the text has been revised in response to student comments on earlier editions and the increased availability of simulation software The revisions include the addition of several new examples of models for the dynamics of systems ranging from an aerosol spray to a spherical robot The primer has three intended audiences undergraduate students enrolled in an introductory course on engineering dynamics graduate students who are interesting in refreshing their knowledge and instructors Review of Second Edition The book is carefully written and provides a good introduction to the subject The main objective of this primer is to reduce the gap between the theoretical framework and an undergraduate student's ability to solve typical problems of undergraduate dynamics Well selected problems illustrate a systematic four step methodology for solving problems from the dynamics of single particles of systems of particles of a single rigid body and of a system of particles and rigid bodies At the end of each chapter some illustrative examples were added Franz Selig Zentralblatt MATH Vol 1201 2011 Engineering Dynamics Roger F. Gans, 2013-03-22 This engineering dynamics textbook is aimed at

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exposition of the dynamics of mechanical systems from an engineering perspective Engineering Mechanics Robert W. Soutas-Little, D. J. Inman, Daniel S. Balint, 2008 Focusing on the conceptual understanding of mechanics this exciting new text addresses developments in the methods of analyzing mechanics problems It fully incorporates the highly sophisticated computational software packages currently available to students The text provides transition material to higher level courses as well as a wealth of problems to foster understanding All sample problems and the use of computational software Mathcad MATLAB Mathematica and Maple are presented in four separate manuals one for each software program Each manual explains how to use the software package to solve the example problems in the book

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