

Solution Manual for Kinematics and Dynamics of Machinery, 3/E 3rd Edition Charles E. Wilson, J. Peter Sadler

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Chapter 1 Mechanisms and Machines: Basic Concepts

1.1 a. The ball-joint (spherical pair) has three degrees-of-freedom, the prismatic pair one, and the cylindrical pair two. The number of degrees-of-freedom of the spatial linkage is given by

$$\begin{aligned} DF_{\text{spatial}} &= 6(n_L - n_J - 1) + \sum f_i \\ &= 6(4 - 3 - 1) + 3 + 1 + 2 \\ &= 6 \text{ degrees-of-freedom} \end{aligned}$$

(We do not need the inequality sign for this open-loop chain).

b. Treating the construction equipment schematic as a spatial linkage:

$$\begin{aligned} DF_{\text{spatial}} &= 6(n_L - n_J - 1) + \sum f_i \\ &= 6(9 - 11 - 1) + 9 + 2 \times 2 \end{aligned}$$

$$DF_{\text{spatial}} = -5$$

c. Treating the construction equipment schematic as a planar linkage, where a sliding pair has only one degree-of-freedom in plane motion:

$$\begin{aligned} DF_{\text{planar}} &= 3(n_L - n_J - 1) + \sum f_i \\ DF_{\text{planar}} &= 3(9 - 11 - 1) + 9 + 2 \\ DF_{\text{planar}} &= 2 \end{aligned}$$

d. The planar motion assumption applies if motion occurs in a plane or in a set of parallel planes. The planes of motion of the links must all be parallel. The revolute joint axes must be perpendicular to those planes. These conditions do apply to the construction machinery. The operator controls the linkage via the two hydraulic cylinders.

Kinematics Dynamics Of Machinery Wilson Solution Manual

**John W. Leonard, Albert Nelson
Marquis**



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