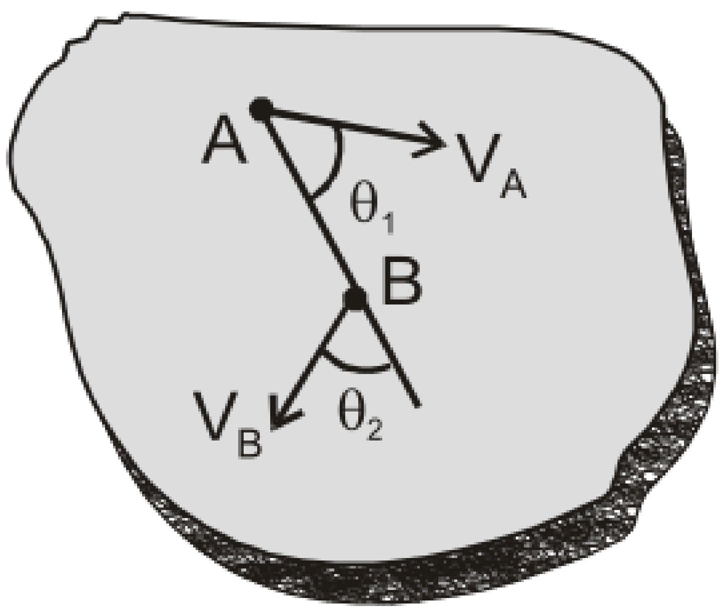
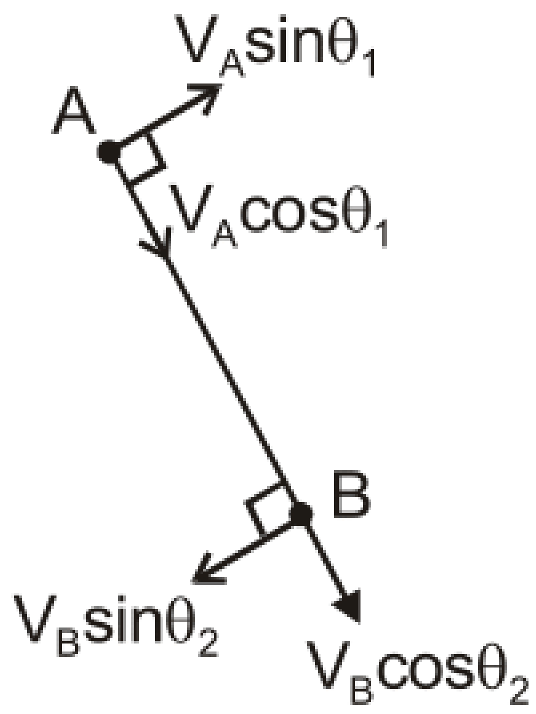
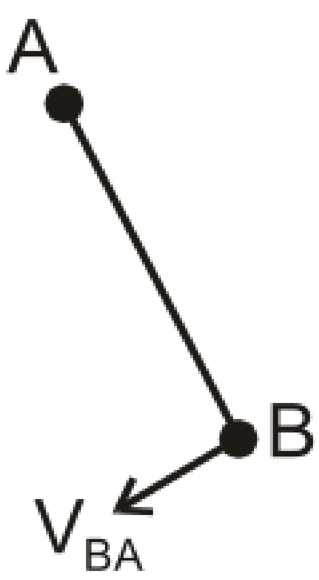
RIGID BODY DYNAMICS

1. RIGID BODY :



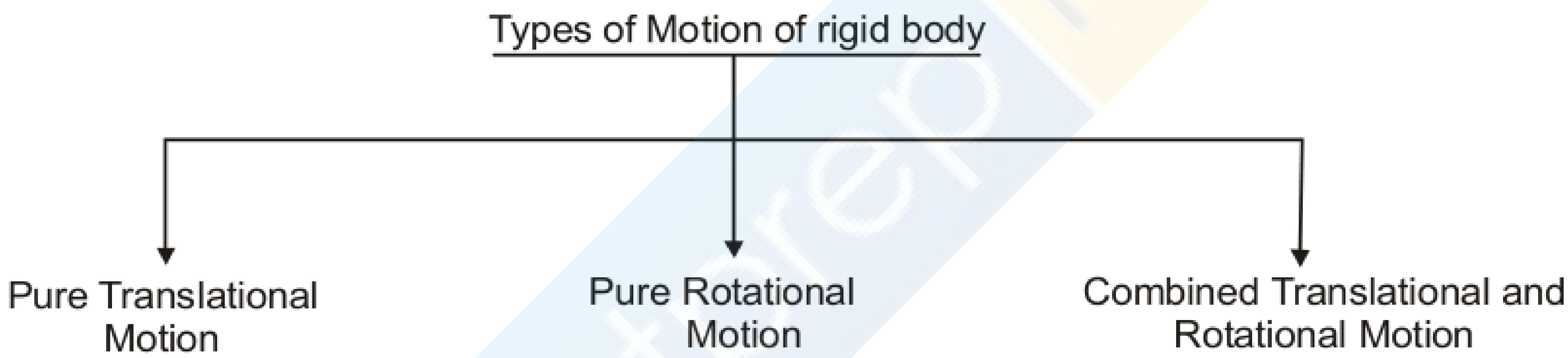




If the above body is rigid

$$V_A \cos\theta_1 = V_B \cos\theta_2$$

V_{BA} = relative velocity of point B with respect to point A.



2. MOMENT OF INERTIA (I) :

Definition : Moment of Inertia is defined as the capability of system to oppose the change produced in the rotational motion of a body.

Moment of Inertia is a scalar positive quantity.

$$I = mr_1^2 + m_2r_2^2 + \ldots\ldots\ldots\ldots$$
$$= I_1 + I_2 + I_3 + \ldots\ldots\ldots\ldots$$

SI units of Moment of Inertia is Kgm^2.

Moment of Inertia of :

2.1 A single particle : $I = mr^2$

where m = mass of the particle

r = perpendicular distance of the particle from the axis about which moment of Inertia is to be calculated

2.2 For many particles (system of particles) :

$$I = \sum_{i=1}^{n} m_i r_i^2$$

$$I = \int dmr^2$$

where dm = mass of a small element
r = perpendicular distance of the particle from the axis

2.4 For a larger object :

$$I = \int dI_{element}$$

where dI = moment of inertia of a small element

3. TWO IMPORTANT THEOREMS ON MOMENT OF INERTIA :

3.1 Perpendicular Axis Theorem

[Only applicable to plane lamina (that means for 2-D objects only)].

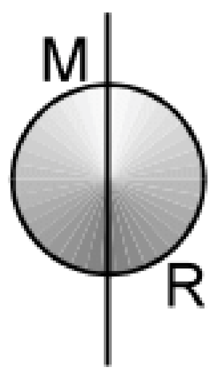
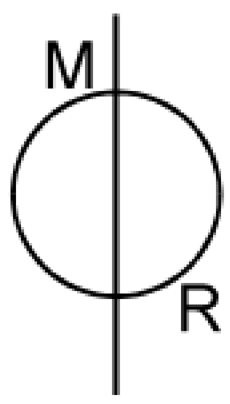
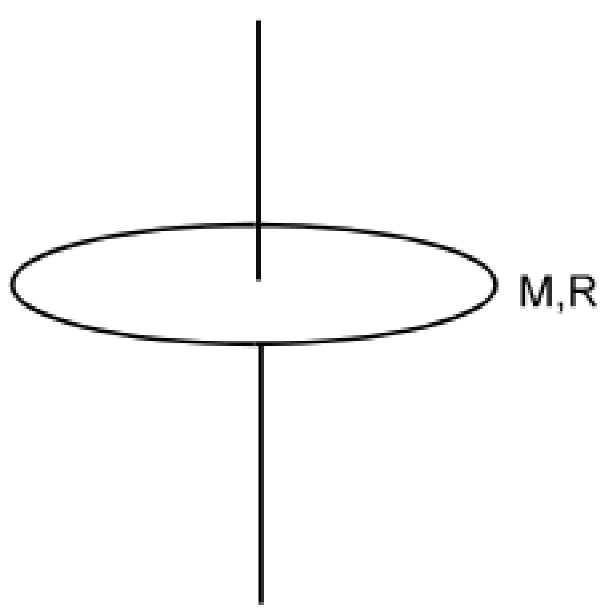
$I_z = I_x + I_y$ (when object is in x-y plane).

3.2 Parallel Axis Theorem

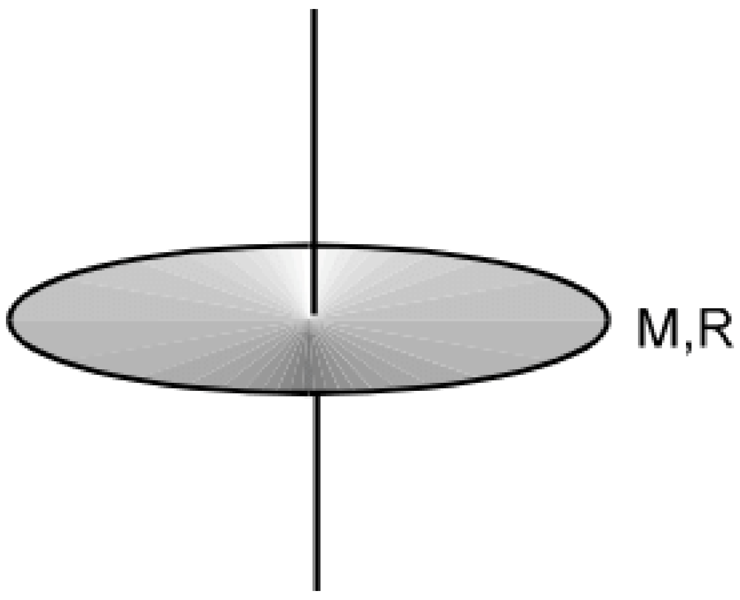
(Applicable to any type of object):

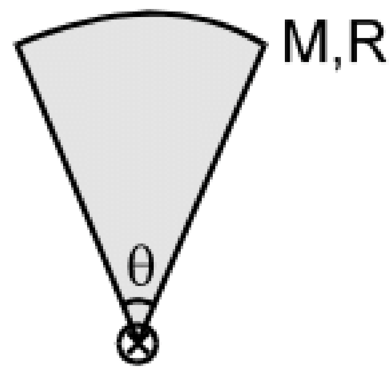
$$I_{AB} = I_{cm} + Md^2$$

List of some useful formula :

Object	Moment of Inertia
 **Solid Sphere**	$\frac{2}{5}MR^2$ (Uniform)
 **Hollow Sphere**	$\frac{2}{3}MR^2$ (Uniform)
	MR^2 (Uniform or Non Uniform)

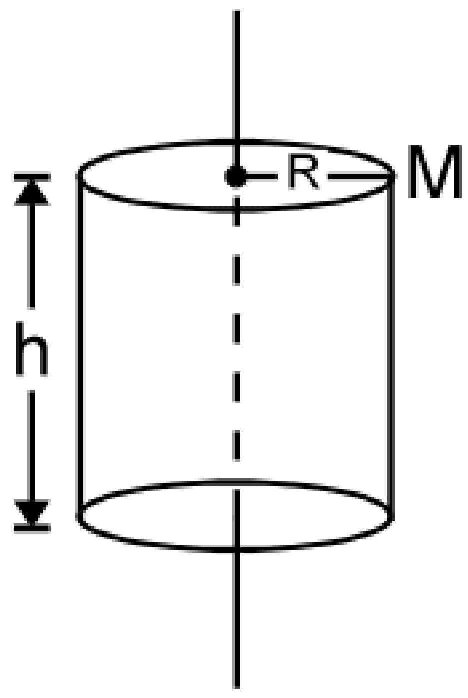
Ring:

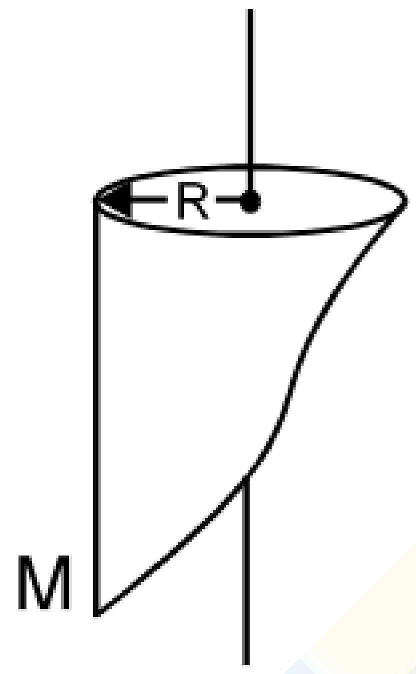




$\frac{MR^2}{2}$ (Uniform)

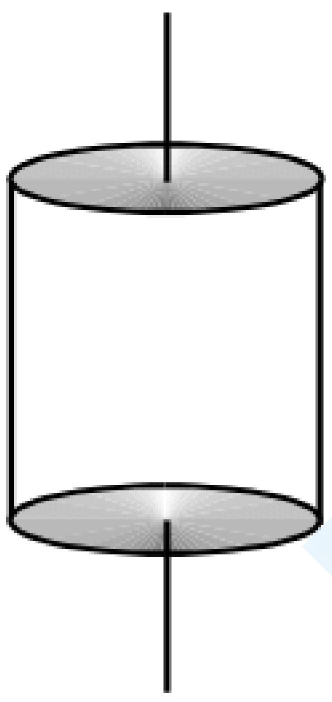
Disc





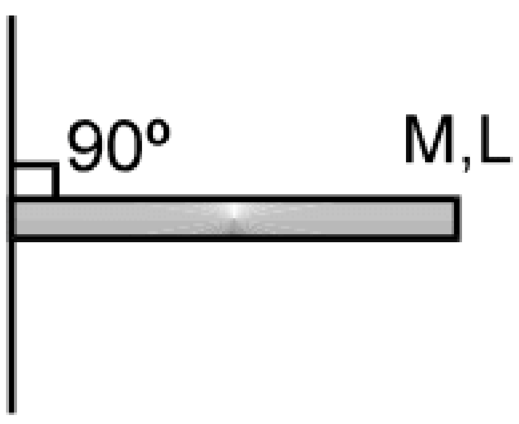
MR^2 (Uniform or Non Uniform)

Hollow cylinder

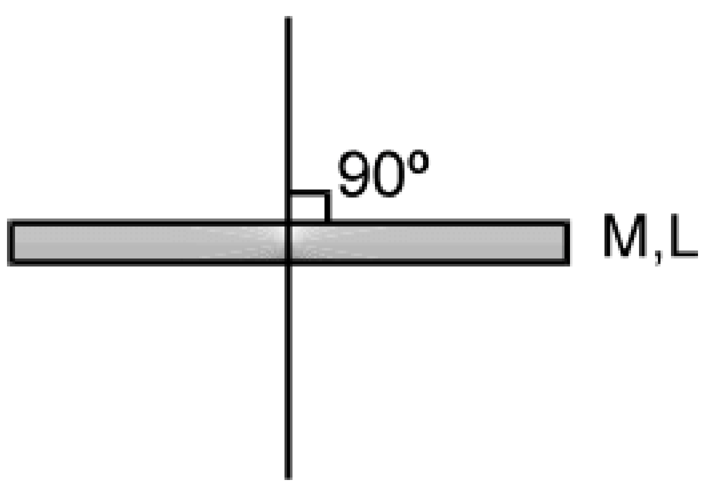


$\frac{MR^2}{2}$ (Uniform)

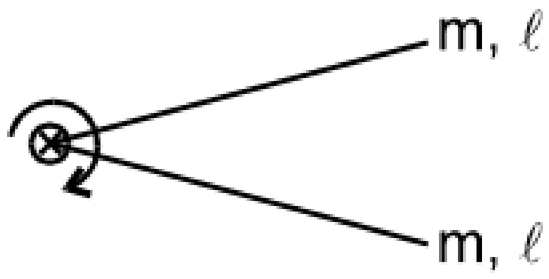
Solid cylinder



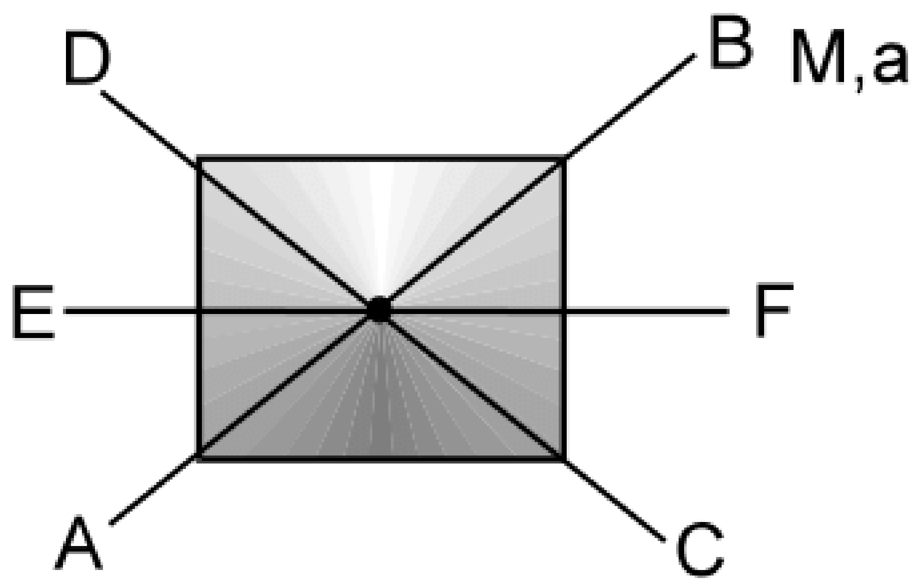
$\frac{ML^2}{3}$ (Uniform)



$\frac{ML^2}{12}$ (Uniform)

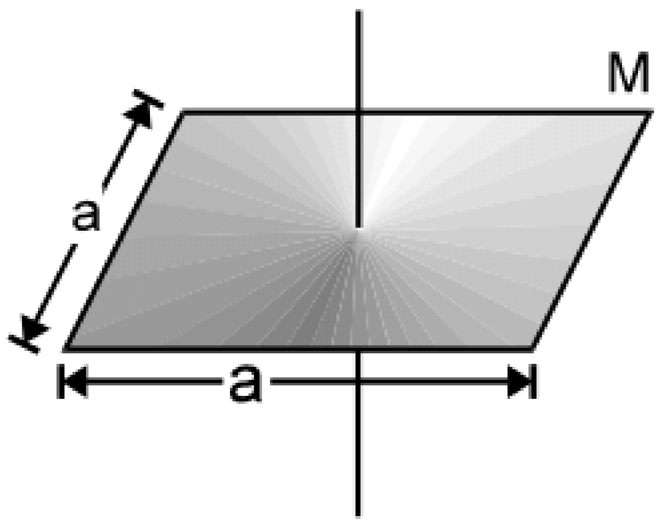


$$\frac{2m\ell^2}{3} \text{ (Uniform)}$$



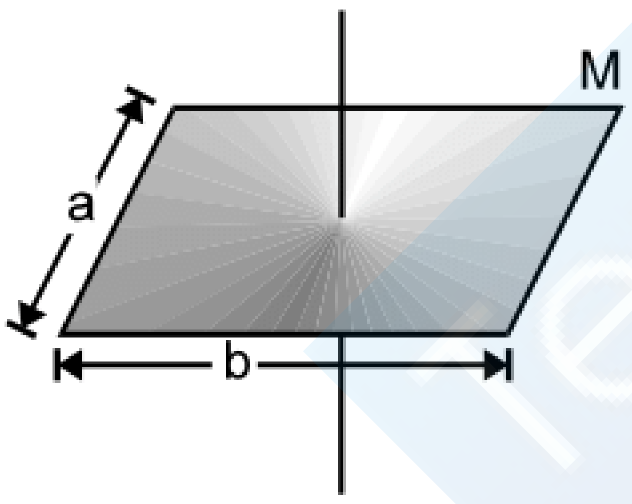
$$I_{AB} = I_{CD} = I_{EF} = \frac{Ma^2}{12} \text{ (Uniform)}$$

Square Plate



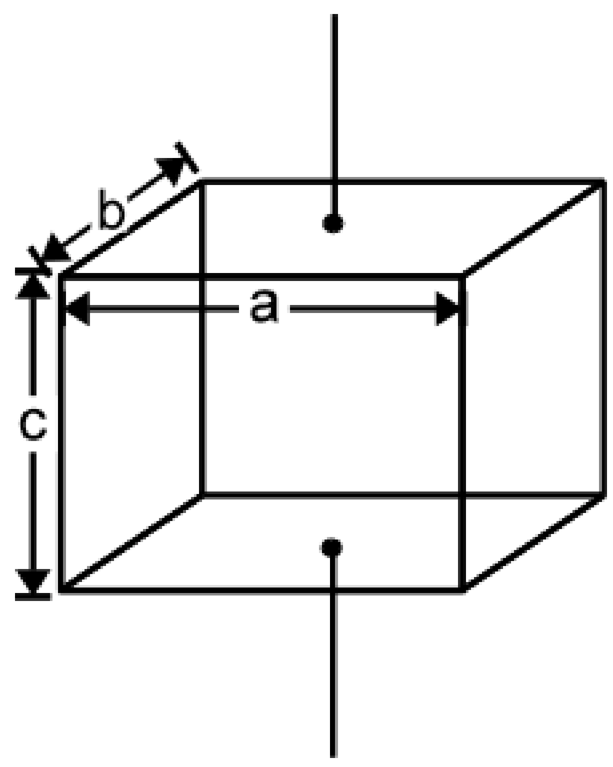
$$\frac{Ma^2}{6} \text{ (Uniform)}$$

Square Plate



$$I = \frac{M(a^2 + b^2)}{12} \text{ (Uniform)}$$

Rectangular Plate



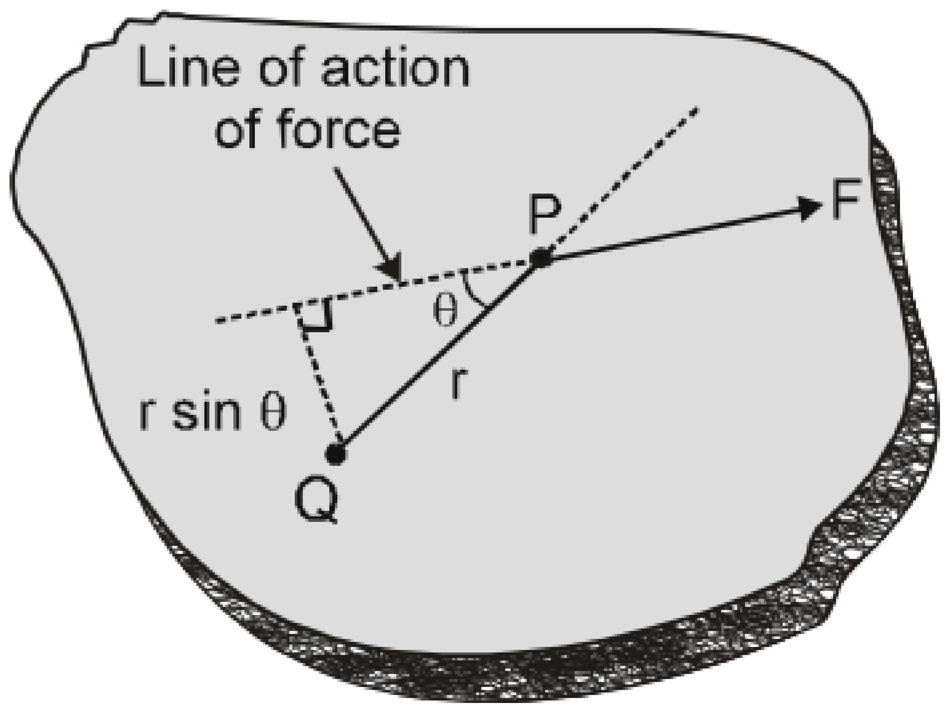
$$\frac{M(a^2 + b^2)}{12} \text{ (Uniform)}$$

4. RADIUS OF GYRATION :

$$I = MK^2$$

5. TORQUE :

$$\vec{\tau} = \vec{r} \times \vec{F}$$

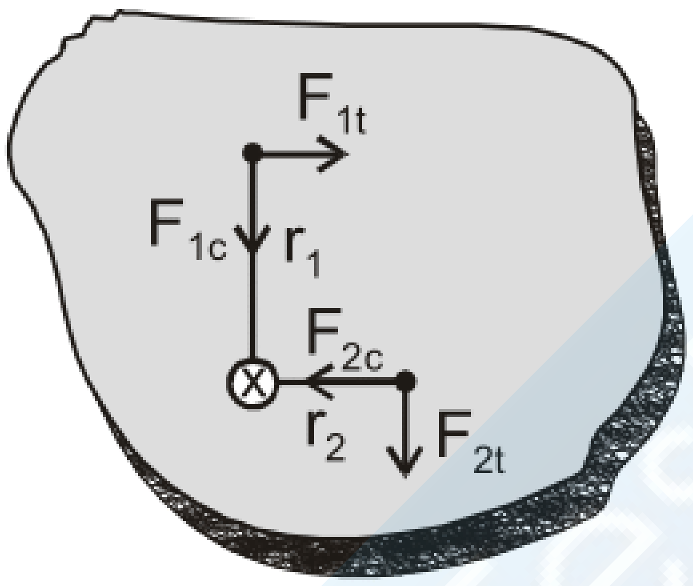


5.5 Relation between 'τ' & 'α ' (for hinged object or pure rotation)

$$\vec{\tau}_{ext}\Big)_{Hinge} = I_{Hinge}\ \vec{\alpha}$$

Where $\vec{\tau}_{ext}\Big)_{Hinge}$ = net external torque acting on the body about Hinge point

I_{Hinge} = moment of Inertia of body about Hinge point



$F_{1t} = M_1 a_{1t} = M_1 r_1 \alpha$

$F_{2t} = M_2 a_{2t} = M_2 r_2 \alpha$

$\tau_{resultant} = F_{1t}\, r_1 + F_{2t}\, r_2 + \ldots\ldots..$

$\qquad\qquad = M_1\, \alpha\, r_1^{\,2} + M_2\, \alpha\, r_2^{\,2} + \ldots\ldots\ldots..$

$\tau_{resultant}\Big)_{external} = I\,\alpha$

Rotational Kinetic Energy = $\dfrac{1}{2}.I.\omega^2$

$\vec{P} = M\vec{v}_{CM} \quad \Rightarrow \quad \vec{F}_{external} = M\vec{a}_{CM}$

Net external force acting on the body has two parts tangential and centripetal.

$$\Rightarrow \quad F_C = ma_C = m\frac{v^2}{r_{CM}} = m\omega^2 r_{CM} \quad \Rightarrow \quad F_t = ma_t = m\alpha\, r_{CM}$$

6. ROTATIONAL EQUILIBRIUM :

For translational equilibrium.

$$\Sigma F_x = 0 \qquad \text{............. (i)}$$

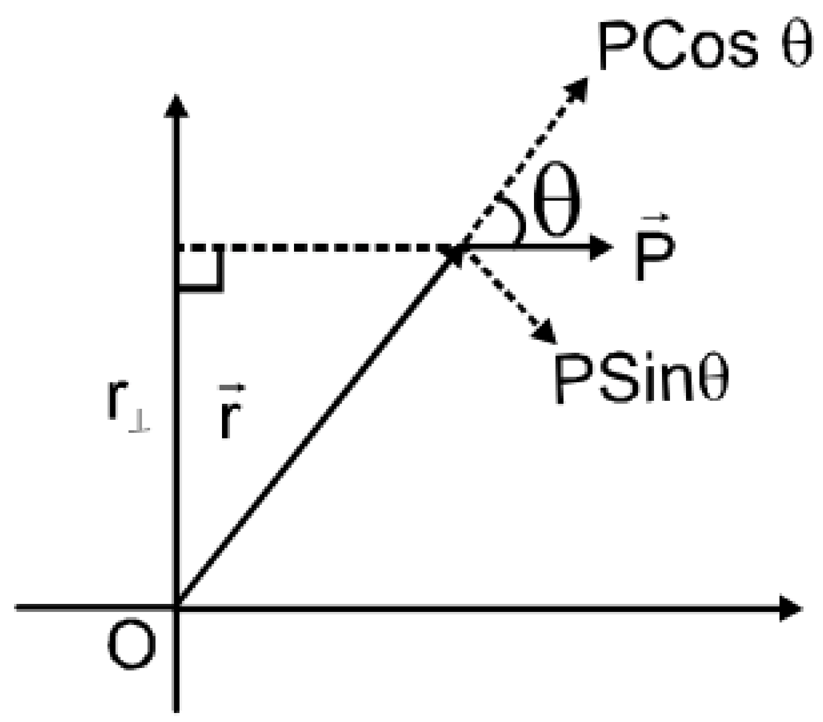
and $$\Sigma F_y = 0 \qquad \text{............. (ii)}$$

The condition of rotational equilibrium is

$$\Sigma \Gamma_z = 0$$

7. ANGULAR MOMENTUM ($\vec{L}$)

7.1 Angular momentum of a particle about a point.



$$\vec{L} = \vec{r} \times \vec{P} \qquad \Rightarrow \qquad L = rp\sin\theta$$

$$|\vec{L}| = r_\perp \times P$$

$$|\vec{L}| = P_\perp \times r$$

7.3 Angular momentum of a rigid body rotating about fixed axis :

$$\vec{L}_H = I_H \vec{\omega}$$

L_H = angular momentum of object about axis H.

I_H = Moment of Inertia of rigid object about axis H.

ω = angular velocity of the object.

7.4 Conservation of Angular Momentum

Angular momentum of a particle or a system remains constant if $\tau_{ext} = 0$ about that point or axis of rotation.

7.5 Relation between Torque and Angular Momentum

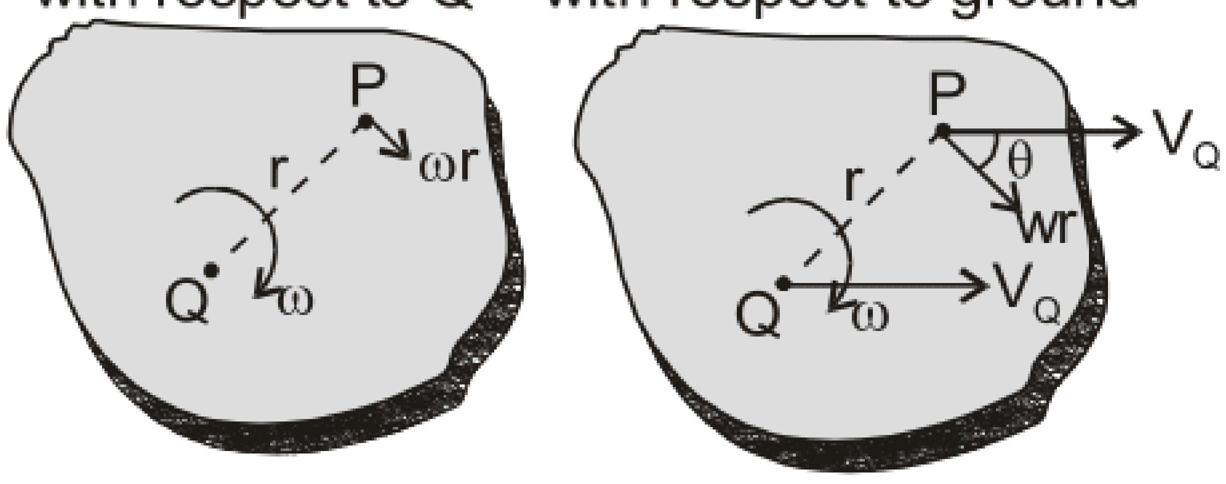
$$\vec{\tau} = \frac{d\vec{L}}{dt}$$

Torque is change in angular momentum

7.6 Impulse of Torque :

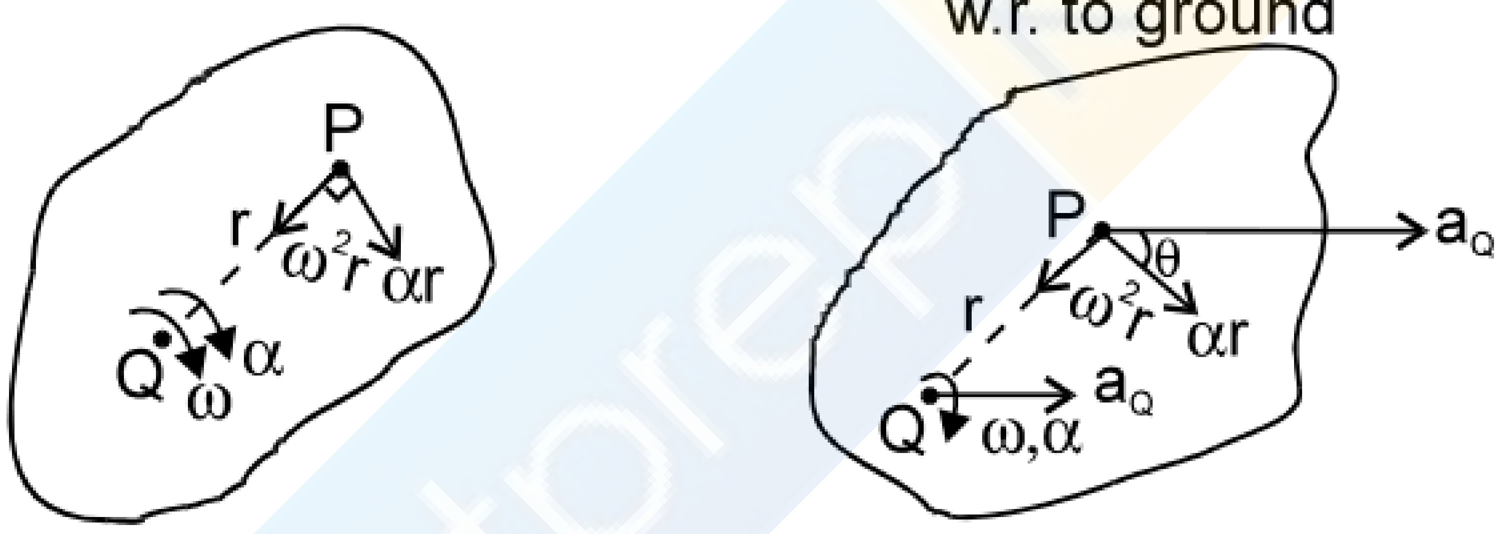
$$\int \tau dt = \Delta J \qquad \Delta J \rightarrow \text{Change in angular momentum.}$$

For a rigid body, the distance between the particles remain unchanged during its motion i.e. $r_{P/Q}$ = constant
For velocities



$$V_P = \sqrt{V_Q^{\,2} + (\omega r)^2 + 2\, V_Q\, \omega r \cos\theta}$$

For acceleration :



θ, ω, α are same about every point of the body (or any other point outside which is rigidly attached to the body).

Dynamics :

$$\vec{\tau}_{cm} = I_{cm}\,\vec{\alpha}\ ,\ \ \vec{F}_{ext} = M\vec{a}_{cm}$$

$\vec{P}_{system} = M\vec{v}_{cm}$,

Total K.E. $= \frac{1}{2} M v_{cm}^2 + \frac{1}{2} I_{cm}\,\omega^2$

Angular momentum axis AB = $\vec{L}$ about C.M. + $\vec{L}$ of C.M. about AB

$$\vec{L}_{AB} = I_{cm}\,\vec{\omega} + \vec{r}_{cm} \times M\vec{v}_{cm}$$