

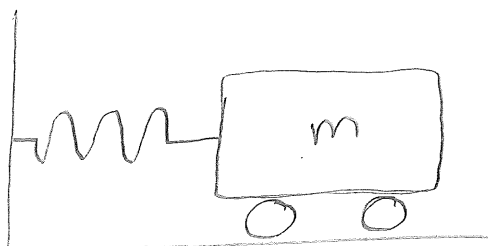
Föreläsning 2

Svängningsrörelse (kap. 12)

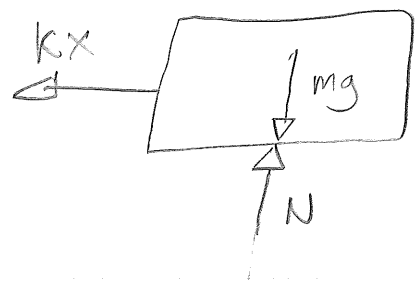
- Fria eller påtvingade svängningar,
– Odämpade eller dämpade

- Visa formulerade samband för dessa fyra situationer.

Fria odämp svängn.



frilägg
 \Rightarrow



$$\boxed{x\text{-led: } m\ddot{x} = -kx} \iff \ddot{x} + \frac{k}{m}x = 0$$

$$y\text{-led: } 0 = N - mg \quad \text{dim: } \frac{m}{s^2} + \underbrace{\left[\frac{k}{m}\right]}_{\frac{1}{s^2}} m$$

$$\triangleright \text{Def: } \frac{k}{m} = \omega_n^2$$

$$\text{Vi vill lösa } \ddot{x} + \omega_n^2 x = 0$$

Ansats: $x = Ae^{\lambda t}$ $[\lambda t] = 1$ $[\lambda] = \frac{1}{[L]} = \frac{1}{s}$

$\Rightarrow \ddot{x} = \lambda^2 Ae^{\lambda t}$

sätt in: $\lambda^2 Ae^{\lambda t} + \omega_n^2 Ae^{\lambda t} = 0$

$\Leftrightarrow Ae^{\lambda t} (\lambda^2 + \omega_n^2) = 0$

kar poli $\lambda^2 + \omega_n^2 = 0 \Rightarrow \lambda = \pm i \omega_n$

$x = A_1 e^{i\omega_n t} + A_2 e^{-i\omega_n t} =$

$= C_1 \cos(\omega_n t) + C_2 \sin(\omega_n t) = C \sin(\omega_n t + \beta) =$

$= C (\sin(\omega_n t) \cos(\beta) + \sin(\beta) \cos(\omega_n t)) =$

Häng med nu verifiera likamedtecknet

$x = \cos \omega_n t [C_1] + \sin \omega_n t [C_2] = \cos \omega_n t [C \sin \beta] + \sin \omega_n t [C \cos \beta]$

$\Rightarrow \left. \begin{matrix} C_1 = C \sin \beta \\ C_2 = C \cos \beta \end{matrix} \right\} \tan \beta = \frac{C_1}{C_2}$

$C^2 (\cos^2 \beta + \sin^2 \beta) = C_1^2 + C_2^2$

Fri odämpad svängning

$x = C_1 \cos(\omega t) + C_2 \sin(\omega t)$

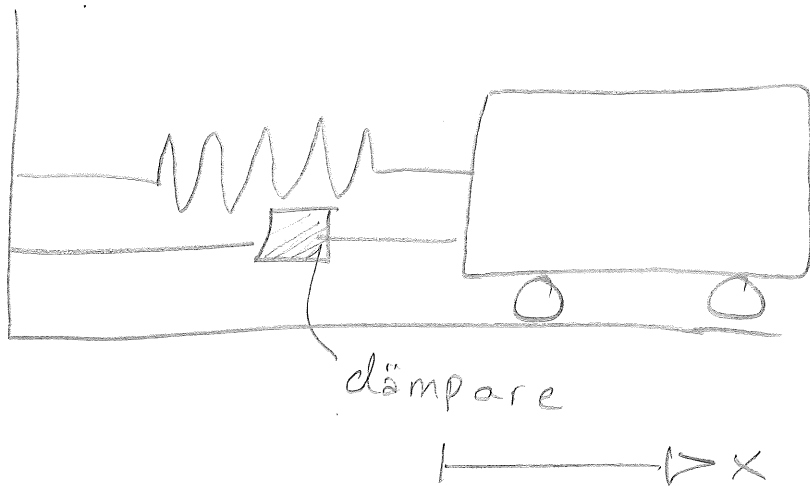
$\dot{x} = -C_1 \omega \sin(\omega t) + C_2 \omega \cos(\omega t)$

$\ddot{x} = -C_1 \omega^2 \cos(\omega t) - C_2 \omega^2 \sin(\omega t)$

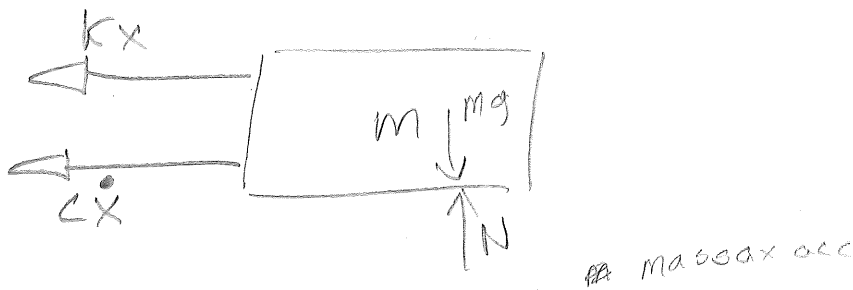
← OKEJ

#e2p2

Fri dämpad svängning



friläggning



massax acc

3

4

x-led: $m\ddot{x} = -kx - c\dot{x}$

$$\ddot{x} + \frac{c}{m}\dot{x} + \frac{k}{m}x = 0$$

$$2\zeta\omega_n$$

$[\zeta]$ är dimensionlös

$$\ddot{x} + 2\zeta\omega_n\dot{x} + \omega_n^2x = 0$$

Ansats: $x = Ae^{\lambda t}$

$$\dot{x} = \lambda Ae^{\lambda t}$$

$$\ddot{x} = \lambda^2 Ae^{\lambda t}$$

Insättning ~~ger~~ : $\ddot{x} + 2\zeta\omega_n\dot{x} + \omega_n^2x = 0$

$$Ae^{\lambda t}(\lambda^2 + 2\zeta\omega_n\lambda + \omega_n^2) = 0$$

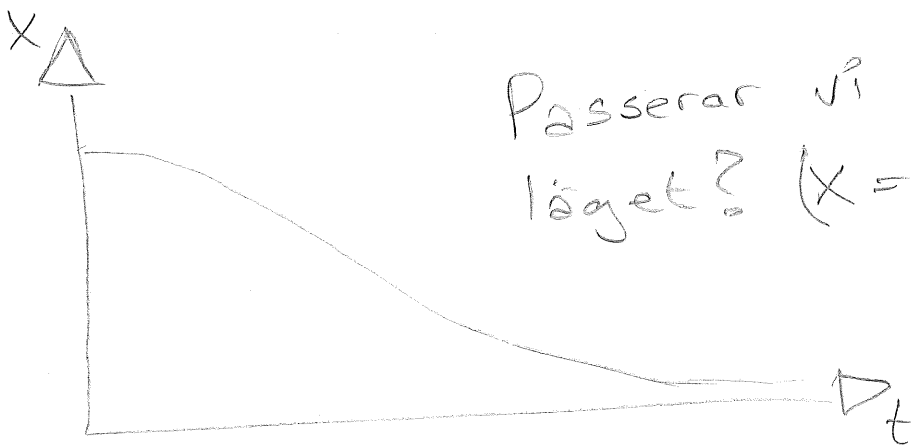
↑
kar. pol.

$$\lambda = -\zeta\omega_n \pm \sqrt{\zeta^2\omega_n^2 - \omega_n^2} = \omega_n(-\zeta \pm \sqrt{\zeta^2 - 1})$$

Om $\zeta > 1$: Stark dämpning

$$\lambda_1, \lambda_2 \in \mathbb{R}$$

$$x = A_1 e^{\lambda_1 t} + A_2 e^{\lambda_2 t} \quad (\text{ingen svängning})$$



Passerar vi jämvikts-
läget? ($x=0$)

$$x = A_1 e^{\lambda_1 t} + A_2 e^{\lambda_2 t} = 0 \Rightarrow e^{(\lambda_1 - \lambda_2)t} = -\frac{A_2}{A_1}$$

bara strängt avtagande.

Om $\zeta = 1$; Kritisk dämpning

$$\lambda_1 = \lambda_2 = -\zeta \omega_n \quad (\text{dubbelrot})$$

$$x = (A_1 + A_2 t) e^{\lambda t}$$

○ $x = 0 \Rightarrow t = -\frac{A_1}{A_2}$ (Jämviktsläget)

○ $\dot{x} = 0 = A_2 e^{\lambda t} + (A_1 + A_2 t) \lambda e^{\lambda t}$

$$A_2 + \lambda(A_1 + A_2 t) = 0$$

$$\Rightarrow \boxed{t = \frac{1}{A_2} \left(-\frac{A_2}{\lambda} - A_1 \right)} \quad (\text{Vändpunkt})$$

○ Vid kritisk dämpning återskapas
jämviktsläget snabbast möjligt

↳ Dimensionering av väg, bilstiftjädra osv.
Sånt vi inte vill att ska pendla.

$$\zeta = 1 \Rightarrow \left. \begin{aligned} 2\zeta \omega_n = 2\omega_n = \frac{c}{m} \\ \omega_n = \sqrt{\frac{k}{m}} \end{aligned} \right\} \begin{aligned} 2\sqrt{\frac{k}{m}} = \frac{c}{m} \\ 2\sqrt{km} = c \end{aligned}$$

Om $\zeta < 1$: Svag dämpning

Imaginärt $\lambda \Rightarrow \cos$ & $\sin \Rightarrow$ svängningar!

$$\lambda_{1,2} = \omega_n \left(-\zeta \pm i \sqrt{1 - \zeta^2} \right)$$

Sätt in

$$x = A_1 e^{\lambda_1 t} + A_2 e^{\lambda_2 t} = A_1 e^{\omega_n (-\zeta + i \sqrt{1 - \zeta^2}) t} + A_2 e^{\omega_n (-\zeta - i \sqrt{1 - \zeta^2}) t}$$

$$= e^{-\omega_n \zeta t} \left(A_1 e^{i \omega_n \sqrt{1 - \zeta^2} t} + A_2 e^{-i \omega_n \sqrt{1 - \zeta^2} t} \right)$$

Def $\omega_n \sqrt{1 - \zeta^2} = \omega_d$ (dämpad egenvinkelfrekvens)

$$\omega_d < \omega_n$$

$$\omega_d = 2\pi f_d = 2\pi \frac{1}{T_d}$$

$$T_d > T_n$$

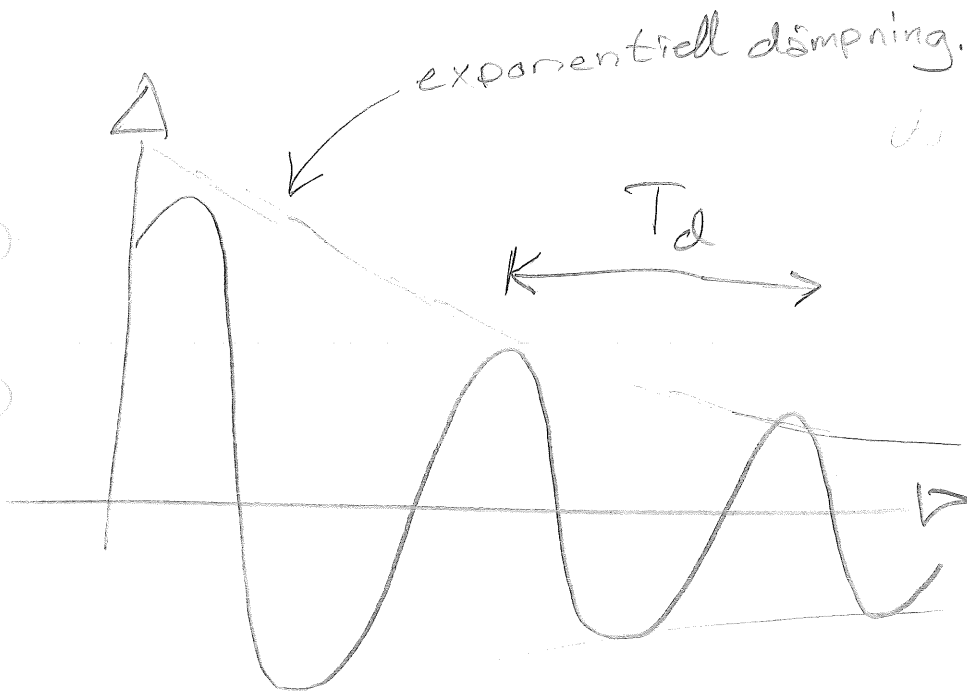
Så

$$x = e^{-\omega_n \zeta t} \left(A_1 e^{i \omega_d t} + A_2 e^{-i \omega_d t} \right)$$

Derivera två ggr!

$$x = e^{-\omega_n \zeta t} (A_1 e^{i\omega_d t} + A_2 e^{-i\omega_d t})$$

$$\dot{x} = e^{-\omega_n \zeta t} [B_1 \sin(\omega_d t + \alpha) + B_2 \cos(\omega_d t + \beta)]$$

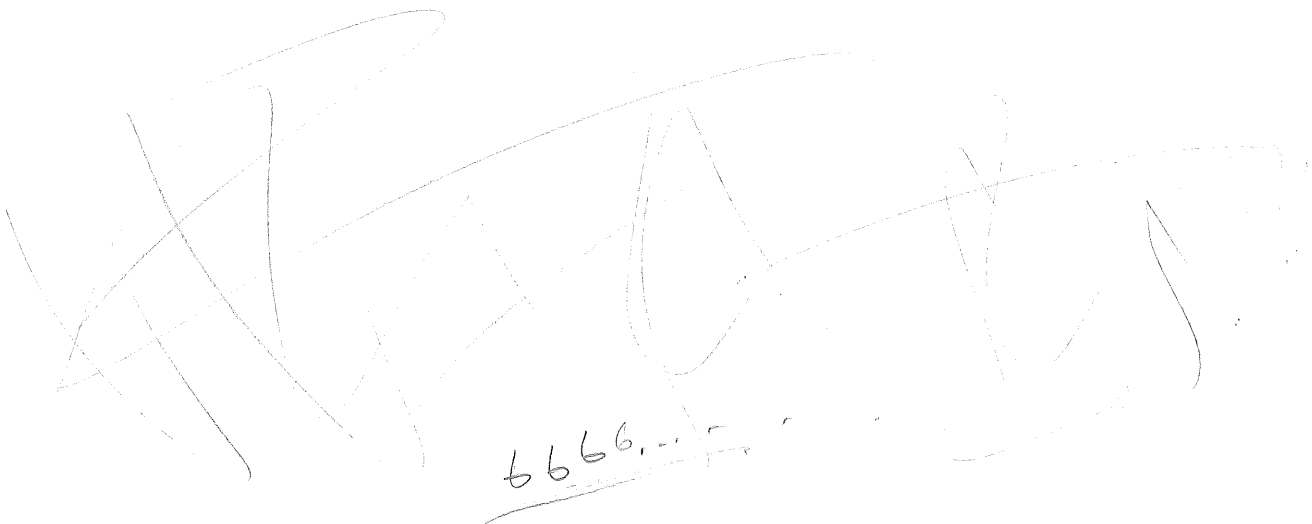


$$\omega_d = \omega_n \sqrt{1 - \zeta^2}$$

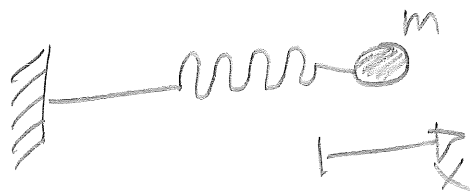
Definition

① dämpfati $C=0 \Rightarrow \zeta = \frac{C}{m} \cdot \frac{1}{2\omega_n} = 0$

$$\Rightarrow \omega_d = \omega_n$$



Exempel



Fjäderkraften konservativ \Rightarrow mekaniska energilagen gäller.

$$T_1 + V_1 = T_0 + V_0 = \text{konstant}$$

$$\Leftrightarrow \frac{1}{2} m \dot{x}^2 + \frac{1}{2} k x^2 = \text{konstant}$$

$$\frac{d}{dt} = \frac{1}{2} m 2 \dot{x} \ddot{x} + \frac{1}{2} k 2 x \dot{x} = 0$$

$$\Leftrightarrow \boxed{m \ddot{x} + kx = 0}$$