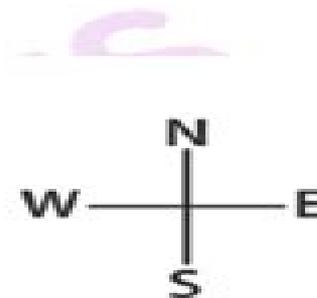


JEE Main Previous Year Solved Questions on Kinematics 2D

Q1: A river is flowing from west to east at a speed of 5 metres per minute. A man on the south bank of the river, capable of swimming at 10 metres per minute in still water, wants to swim across the river in the shortest time. He should swim in a direction.

1. due north
2. 30° east of north
3. 30° west of north
4. 60° east of north

Solution:



Let the time taken to cross the river be t

$$t = \frac{d}{V_s \cos \theta}$$

For the time t to be minimum, $\cos \theta$ should be maximum

θ should be 0

Therefore swimmer should swim due north

Answer: (1) due north

Q2: A particle P is sliding down a frictionless hemispherical bowl. It passes point A at $t = 0$. At this instant of time, the horizontal component of its velocity is v . A bead Q of the same mass as P is ejected from A at $t = 0$ along the horizontal string AB , with speed v . Friction between the bead and the string may be neglected. Let t_p and t_q be the respective times taken by P and Q to reach point B .

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Syed, Mahbubur Rahman



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Solutions to some of the problems in Kinematics Peter Z. Bulkeley, Virgil Moring Faires, 1959

Solving Inverse Kinematics Problems by Decomposition, Classification and Simple Modeling, 2013 Inverse kinematics is a major problem in robotics and computer animation This problem does not always have a unique solution and sometimes there may not be any solution at all The forward relations for kinematics are generally complex which makes it difficult to determine their inverse relation mathematically In other words there is no closed form solution for such problems In this thesis we solve the inverse kinematics for a manipulator with six links and six variable joints where the position and orientation of the end effector are the output and the joint angles are the input We have used an approach based on decomposition of output space into cells with the input space correspondingly divided into regions Solutions are identified using a clustering method in which the relationships between data in an output cell and clusters in the corresponding input region are modeled by simple polynomials The method has been implemented and evaluated for accuracy and compared with other methods for solving inverse kinematics problem The results show that the proposed method is fast and accurate in finding all the solutions when they exist

Kinematics, Dynamics, and Design of Machinery Kenneth J. Waldron, Gary L. Kinzel, Sunil K. Agrawal, 2016-04-25 Kinematics Dynamics and Design of Machinery Third Edition presents a fresh approach to kinematic design and analysis and is an ideal textbook for senior undergraduates and graduates in mechanical automotive and production engineering Presents the traditional approach to the design and analysis of kinematic problems and shows how GCP can be used to solve the same problems more simply Provides a new and simpler approach to cam design Includes an increased number of exercise problems Accompanied by a website hosting a solutions manual teaching slides and MATLAB programs

Solutions for Problems Basic in Graphical Kinematics Harold B. Kepler, 1973

Game Inverse Kinematics Kenwright, 2020-07-29 Game Inverse Kinematics a practical introduction presents a beginners guide to getting started with inverse kinematics In this book a broad range of inverse kinematic techniques are explained from a practical perspective The reader is introduced to the exciting topic using practical examples The book explains basic principles all the way through to testing and coding while illustrating and explaining working samples to give the reader a solid grasp of the topic Master the basic maths and principles needed to incorporate inverse kinematics into your simulation Code 2D and 3D inverse kinematic simulations such as articulated characters and pulley systems Construct kinematic structures for generated character poses Develop an understanding for simulation inaccuracies numerical problems approximations and how to deal with them This book is intended to serve as an introductory text but it also offers experienced developers a useful perspective on aspects of inverse kinematic techniques with which they may not

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