

10.5

The boat translates only. Thus all points on the boat have the same virtual displacement.

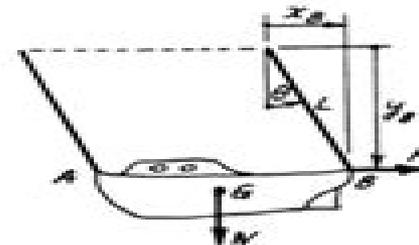
$$x_B = L \sin \theta \quad \therefore \delta x_B = L \cos \theta \delta \theta$$

$$y_B = L \cos \theta \quad \therefore \delta y_B = \delta y_G = -L \sin \theta \delta \theta$$

$$\delta U = P \delta x_B + W \delta y_G = [PL \cos \theta + W(-L \sin \theta)] \delta \theta$$

$$\delta U = 0: PL \cos \theta - WL \sin \theta = 0$$

$$\therefore P = W \tan \theta = 17.658 \tan 20^\circ = 6.43 \text{ kN} \rightarrow$$



10.6

Note that BE remains vertical.

$$x_D = 50 \cos \theta \quad \therefore \delta x_D = -50 \sin \theta \delta \theta$$

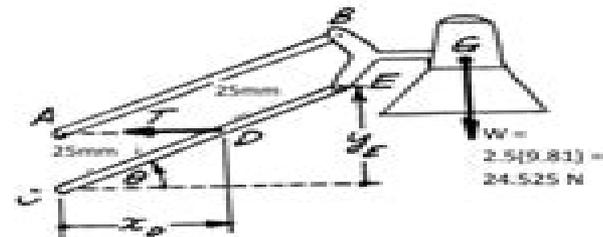
$$y_E = 100 \sin \theta \quad \therefore \delta y_E = \delta y_G = 100 \cos \theta \delta \theta$$

$$\delta U = -T \delta x_D - W \delta y_G$$

$$= [T(\sin \theta) - (24.525)(100 \cos \theta)] \delta \theta$$

$$\delta U = 0: 50T \sin \theta - 2452.5 \cos \theta = 0$$

$$\therefore T = 49.05 \cot \theta = 49.05 \cot 30^\circ = 85 \text{ N}$$



10.7

The mechanism has a single DOF. Choose θ as the kinematically independent variable.

θ and α are related by the geometric constraint

$$150 \sin \theta + 80 \sin \alpha = 150$$

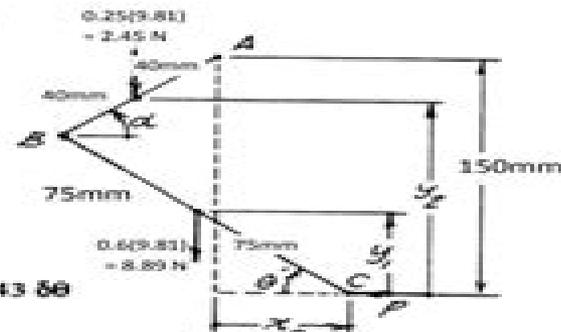
$$\therefore \sin \alpha = \frac{150(1 - \sin \theta)}{80} = \frac{15(1 - \sin 40^\circ)}{80} = 0.6698$$

$$\therefore \alpha = 42.05^\circ$$

The geometric constraint also yields

$$150 \cos \theta \delta \theta + 80 \cos \alpha \delta \alpha = 0$$

$$\therefore \delta \alpha = -\frac{150 \cos \theta}{80 \cos \alpha} \delta \theta = -\frac{15 \cos 40^\circ}{8 \cos 42.05^\circ} \delta \theta = -1.9343 \delta \theta$$



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