$ax^2 + bx + c = 0,$

$$x = \frac{-b \pm \sqrt{b^2 - 4ac}}{2a}$$

$2\pi \text{ rad} \div 360 =$

$$\frac{\sin\theta a}{a} = \frac{\sin\theta b}{b} = \frac{\sin\theta c}{c}$$

$c^2 = a^2 + b^2 - 2ab\cos\theta c$

$\theta_a + \theta_b + \theta_c = \pi \ (180)$

$\sin\theta = \frac{b}{c} = \frac{\text{Opposite}}{\text{Hypotenuse}}$

$\cos\theta = \frac{a}{c} = \frac{\text{Adjacent}}{\text{Hypotenuse}}$

$\tan\theta = \frac{b}{a} = \frac{\text{Opposite}}{\text{Adjacent}}$

$\sin(\alpha \pm \beta) = \sin\alpha\cos\beta \pm \cos\alpha\sin\beta$

$\cos(\alpha \pm \beta) = \cos\alpha\cos\beta \mp \sin\alpha\sin\beta$

$W = mg$

$g = 32.2 \text{ ft/sec}^2 = 9.81 \text{ m/sec}^2$

$N = \frac{kg\text{-}m}{sec^2}$ slug $= \frac{lb}{(ft/sec^2)}$

Units for moment of a force

U.S.Customary	SI
ft -lb or in. -lb	N·m

Chapter 2: Force Vectors

$R = \sum F,$ $F = F\hat{\lambda}$

$\hat{\lambda}_{AB} = \frac{\vec{r}_{AB}}{|\vec{r}|}$

$= \frac{\Delta x\,\hat{i} + \Delta y\,\hat{j} + \Delta z\,\hat{k}}{\sqrt{(\Delta x)^2 + (\Delta y)^2 + (\Delta z)^2}}$

$\hat{\lambda}_{AB} = \cos\theta x\,\hat{i} + \cos\theta y\,\hat{j} + \cos\theta z\,\hat{k}$

$\hat{\lambda}_{AB} = \sin\theta y\cos\varphi\,\hat{i} + \cos\theta y\,\hat{j} + \sin\theta y\sin\varphi\,\hat{k}$

$\cos^2\theta_x + \cos^2\theta_y + \cos^2\theta_z = 1$

$F = F_x\hat{i} + F_y\hat{j}$

$= F\cos\theta\,\hat{i} + F\sin\theta\,\hat{j}$

$= F\angle\theta$

Chapter 3: Equilibrium of Particles

$\sum F = \sum F_x\,\hat{i}$

$+ \sum F_y\,\hat{j}$

$+ \sum F_z\,\hat{k} = 0$

$\hat{i}: \sum F_x = 0$

$\hat{j}: \sum F_y = 0$

$\hat{k}: \sum F_z = 0$

Chapter 4: Moments of a Force

The moment of F about point A

$M_A = \vec{r} \times F,$ $|M_A| = d_\perp F$

where $\vec{r}$ is a position vector from P to any point on the line of action of F

$M_A = (Fr)\sin\phi = F(\sin\phi) = F d_\perp,$

$M_A = (Fr)\sin\phi = (\sin\phi)F = \phi r$ $F \perp r.$

$M_A = \vec{r} \times F_1 + F_2$

$= \vec{r} \times F_1 + \vec{r} \times F_2$

Moment about a line:

$M_{AB} = \hat{\lambda}_{AB} \cdot M = \hat{\lambda}_{AB} \cdot ( )$

$= \cos\theta$

$= |MP|$

$M_{AB} = \begin{vmatrix} \lambda x & \lambda y & \lambda z \\ rx & ry & rz \\ Fx & Fy & Fz \end{vmatrix}$

Equivalent Force-Couple System:

$R = \sum F,$

$M_O = \sum M_O$

$= \sum (\vec{r} \times F) + \sum M_{couples}$

Equivalent Systems:

$\sum F_{System_1} = \sum F_{System_2}$

$\sum M_B_{System_1} = \sum M_B_{System_2}$

Chapter 5: Equilibrium of Rigid Bodies

$\sum F = 0,$ and $\sum M_B = 0$

$\hat{i}: \sum F_x = 0$

$\hat{j}: \sum F_y = 0$

$\hat{k}: \sum F_z = 0$

$\hat{i}: \sum M_x = 0$

$\hat{j}: \sum M_y = 0$

$\hat{k}: \sum M_z = 0$

2D Planar:

$\rightarrow \sum F_x = 0$

$\uparrow \sum F_y = 0$

$\circlearrowleft \sum M_P = 0$

Reaction forces prevent translation:
Reaction moments prevent rotation

Chapter 7: Internal Forces and Moments

In two-dimensions:

N = Normal Axial Force
V = Transverse Shear Force
M = Bending Moment

$$\frac{dV}{dx} = -w,\quad \frac{dM}{dx} = V$$

$$\frac{d^2M}{dx^2} = -w(x)$$

Concentrated force P,
shear discontinuity (jump):

$V_+ - V_- = -P$

Concentrated couple MC,
moment jump:

$M_+ - M_- = -MC$

In three-dimensions:

Nx = Axial Force
Vy = Shear Force in y-direction
Vz = Shear Force in z-direction
Tx = Torque about the x-axis
My = Moment about the y-axis
Mz = Moment about the z-axis

Distributed loads w(x):

$$F = \int_L w(x)\,dx$$

$$F\bar{x} = M = \int_L x\,w(x)\,dx$$

Effect of w(x) is statically equivalent to resultant F at position $\bar{x}$.

Chapter 8: Friction

$F_f \leq (F_f)_{max}$ static $= \mu_s F_N$

If at the max limit, on the verge of sliding and impending motion,

$F_f = \mu_s F_N$

Belt Friction: $\dfrac{T_1}{T_2} = e^{\mu\beta}$

Spring Forces and Torques

$F_s = k_L(L_1 - L)$

$M_s = k_\theta(\theta_1 - \theta)$

Chapter 11: Virtual Work

$\delta U = \delta r \cdot F + \delta\theta \cdot M = 0$

Virtual Power:

$\delta V = \delta v \cdot F + \delta\omega \cdot M = 0$

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L Cohen

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