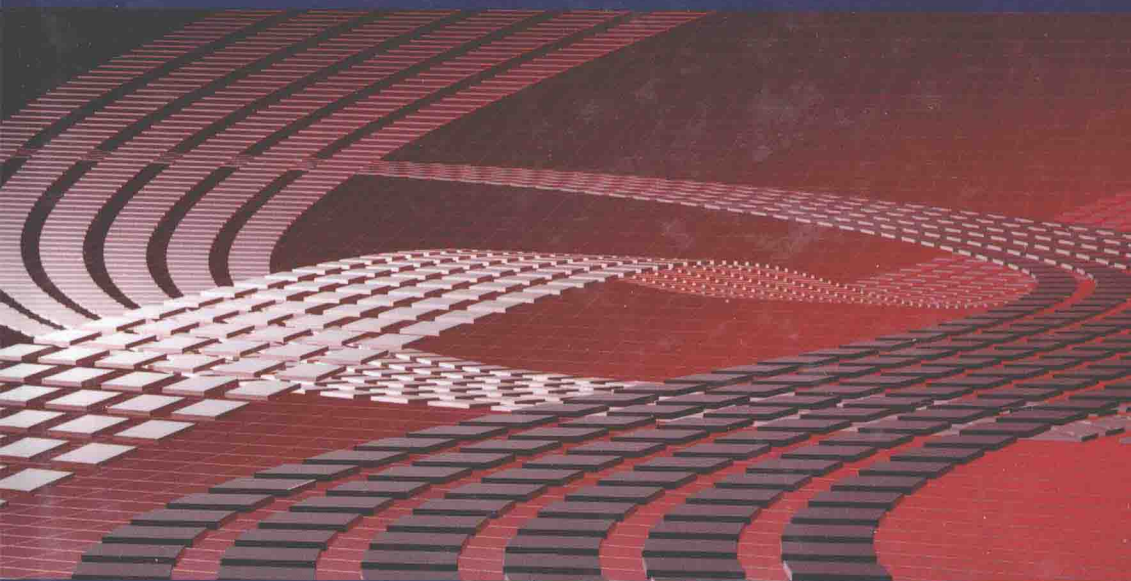


MECHANICAL ENGINEERING AND SOLID MECHANICS SERIES



Mechanical Shock

Mechanical Vibration and Shock Analysis
Revised and Updated 3rd Edition
Volume 2

Christian Lalanne

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Mechanical Vibration and Shock Analysis

Third edition – Volume 2

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Foreword to Series

In the course of their lifetime simple items in everyday use such as mobile telephones, wristwatches, electronic components in cars or more specific items such as satellite equipment or flight systems in aircraft, can be subjected to various conditions of temperature and humidity, and more particularly to mechanical shock and vibrations, which form the subject of this work. They must therefore be designed in such a way that they can withstand the effects of the environmental conditions to which they are exposed without being damaged. Their design must be verified using a prototype or by calculations and/or significant laboratory testing.

Sizing, and later, testing are performed on the basis of specifications taken from national or international standards. The initial standards, drawn up in the 1940s, were blanket specifications, often extremely stringent, consisting of a sinusoidal vibration, the frequency of which was set to the resonance of the equipment. They were essentially designed to demonstrate a certain standard resistance of the equipment, with the implicit hypothesis that if the equipment survived the particular environment it would withstand, undamaged, the vibrations to which it would be subjected in service. Sometimes with a delay due to a certain conservatism, the evolution of these standards followed that of the testing facilities: the possibility of producing swept sine tests, the production of narrowband random vibrations swept over a wide range and finally the generation of wideband random vibrations. At the end of the 1970s, it was felt that there was a basic need to reduce the weight and cost of on-board equipment and to produce specifications closer to the real conditions of use. This evolution was taken into account between 1980 and 1985 concerning American standards (MIL-STD 810), French standards (GAM EG 13) or international standards (NATO), which all recommended the *tailoring of tests*. Current preference is to talk of the *tailoring of the product to its environment* in order to assert more clearly that the environment must be taken into account from the very start of the project, rather than to check the behavior of the material *a*

posteriori. These concepts, originating with the military, are currently being increasingly echoed in the civil field.

Tailoring is based on an analysis of the life profile of the equipment, on the measurement of the environmental conditions associated with each condition of use and on the synthesis of all the data into a simple specification, which should be of the same severity as the actual environment.

This approach presupposes a proper understanding of the mechanical systems subjected to dynamic loads and knowledge of the most frequent failure modes.

Generally speaking, a good assessment of the stresses in a system subjected to vibration is possible only on the basis of a finite element model and relatively complex calculations. Such calculations can only be undertaken at a relatively advanced stage of the project once the structure has been sufficiently defined for such a model to be established.

Considerable work on the environment must be performed independently of the equipment concerned either at the very beginning of the project, at a time where there are no drawings available, or at the qualification stage, in order to define the test conditions.

In the absence of a precise and validated model of the structure, the simplest possible mechanical system is frequently used consisting of mass, stiffness and damping (a linear system with one degree of freedom), especially for:

- the comparison of the severity of several shocks (shock response spectrum) or of several vibrations (extreme response and fatigue damage spectra);
- the drafting of specifications: determining a vibration which produces the same effects on the model as the real environment, with the underlying hypothesis that the equivalent value will remain valid on the real, more complex structure;
- the calculations for pre-sizing at the start of the project;
- the establishment of rules for analysis of the vibrations (choice of the number of calculation points of a power spectral density) or for the definition of the tests (choice of the sweep rate of a swept sine test).

This explains the importance given to this simple model in this work of five volumes on “Mechanical Vibration and Shock Analysis”.

Volume 1 of this series is devoted to *sinusoidal vibration*. After several reminders about the main vibratory environments which can affect materials during their working life and also about the methods used to take them into account,

following several fundamental mechanical concepts, the responses (relative and absolute) of a mechanical one-degree-of-freedom system to an arbitrary excitation are considered, and its transfer function in various forms are defined. By placing the properties of sinusoidal vibrations in the contexts of the real environment and of laboratory tests, the transitory and steady state response of a single-degree-of-freedom system with viscous and then with non-linear damping is evolved. The various sinusoidal modes of sweeping with their properties are described, and then, starting from the response of a one-degree-of-freedom system, the consequences of an unsuitable choice of sweep rate are shown and a rule for choice of this rate is deduced from it.

Volume 2 deals with *mechanical shock*. This volume presents the shock response spectrum (SRS) with its different definitions, its properties and the precautions to be taken in calculating it. The shock shapes most widely used with the usual test facilities are presented with their characteristics, with indications how to establish test specifications of the same severity as the real, measured environment. A demonstration is then given on how these specifications can be made with classic laboratory equipment: shock machines, electrodynamic exciters driven by a time signal or by a response spectrum, indicating the limits, advantages and disadvantages of each solution.

Volume 3 examines the analysis of *random vibration* which encompasses the vast majority of the vibrations encountered in the real environment. This volume describes the properties of the process, enabling simplification of the analysis, before presenting the analysis of the signal in the frequency domain. The definition of the power spectral density is reviewed, as well as the precautions to be taken in calculating it, together with the processes used to improve results (windowing, overlapping). A complementary third approach consists of analyzing the statistical properties of the time signal. In particular, this study makes it possible to determine the distribution law of the maxima of a random Gaussian signal and to simplify the calculations of fatigue damage by avoiding direct counting of the peaks (Volumes 4 and 5). The relationships, that provide the response of a one-degree-of-freedom linear system to a random vibration, are established.

Volume 4 is devoted to the calculation of *damage fatigue*. It presents the hypotheses adopted to describe the behavior of a material subjected to fatigue, the laws of damage accumulation and the methods for counting the peaks of the response (used to establish a histogram when it is impossible to use the probability density of the peaks obtained with a Gaussian signal). The expressions of mean damage and its standard deviation are established. A few cases are then examined using other hypotheses (mean not equal to zero, taking account of the fatigue limit, non-linear accumulation law, etc.). The main laws governing low cycle fatigue and fracture mechanics are also presented.

Volume 5 is dedicated to presenting the method of *specification development* according to the principle of tailoring. The extreme response and fatigue damage spectra are defined for each type of stress (sinusoidal vibrations, swept sine, shocks, random vibrations, etc.). The process for establishing a specification as from the lifecycle profile of the equipment is then detailed taking into account the uncertainty factor (uncertainties related to the dispersion of the real environment and of the mechanical strength) and the test factor (function of the number of tests performed to demonstrate the resistance of the equipment).

First and foremost, this work is intended for engineers and technicians working in design teams responsible for sizing equipment, for project teams given the task of writing the various sizing and testing specifications (validation, qualification, certification, etc.) and for laboratories in charge of defining the tests and their performance following the choice of the most suitable simulation means.

Introduction

Transported or on-board equipment is very frequently subjected to mechanical shocks in the course of its useful lifetime (material handling, transportation, etc.). This kind of environment, although of extremely short duration (from a fraction of a millisecond to a few dozen milliseconds), is often severe and cannot be ignored.

The initial work on shocks was carried out in the 1930s on earthquakes and their effect on buildings. This resulted in the notion of the shock response spectrum. Testing on equipment started during World War II. Methods continued to evolve with the increase in power of exciters, making it possible to create synthetic shocks, and again in the 1970s, with the development of computerization, enabling tests to be directly conducted on the exciter employing a shock response spectrum.

After a brief recapitulation of the shock shapes most often used in tests and of the possibilities of Fourier analysis for studies taking account of the environment (Chapter 1), Chapter 2 presents the shock response spectrum with its numerous definitions and calculation methods.

Chapter 3 describes all the properties of the spectrum showing that important characteristics of the original signal can be drawn from it, such as its amplitude or the velocity change associated with the movement during the shock.

The shock response spectrum is the ideal tool for drafting specifications. Chapter 4 details the process which makes it possible to transform a set of shocks recorded in the real environment into a specification of the same severity, and presents a few other methods proposed in the literature.

Knowledge of the kinematics of movement during a shock is essential to the understanding of the mechanism of shock machines and programmers. Chapter 5 gives the expressions for velocity and displacement, according to time, for classic shocks, depending on whether they occur in impact or impulse mode.

Chapter 6 describes the principle of the shock machines currently most widely used in laboratories and their associated programmers. To reduce costs by restricting the number of changes in test facilities, specifications expressed in the form of a simple shock (half-sine, rectangle, sawtooth with a final peak) can occasionally be tested using an electrodynamic exciter. Chapter 7 sets out the problems encountered, stressing the limitations of such means, together with the consequences of modification, that have to be made to the shock profile, on the quality of the simulation.

Determining a simple-shaped shock of the same severity as a set of shocks, on the basis of their response spectrum, is often a delicate operation. Thanks to progress in computerization and control facilities, this difficulty can occasionally be overcome by expressing the specification in the form of a response spectrum and by controlling the exciter directly from that spectrum. In practical terms, as the exciter can only be driven with a signal that is a function of time, the software of the control rack determines a time signal with the same spectrum as the specification displayed. Chapter 8 describes the principles of the composition of the equivalent shock, gives the shapes of the basic signals most often used, with their properties, and emphasizes the problems that can be encountered, both in the constitution of the signal and with respect to the quality of the simulation obtained.

Pyrotechnic devices or equipment (cords, valves, etc.) are very frequently used in satellite launchers due to the very high degree of accuracy that they provide in operating sequences. Shocks induced in structures by explosive charges are extremely severe, with very specific characteristics. Their simulation in the laboratory requires specific means, as described in Chapter 9.

Containers must protect the equipment carried in them from various forms of disturbance related to handling and possible accidents. Tests designed to qualify or certify containers include shocks that are sometimes difficult or even impossible to produce given the combined weight of the container and its content. One relatively widely used possibility consists of performing shocks on scale models, with scale factors of the order of 4 or 5, for example. This same technique can be applied, although less frequently, to certain vibration tests. At the end of this volume, the Appendix summarizes the laws of similarity adopted to define the models and to interpret the test results.

List of Symbols

The list below gives the most frequent definition of the main symbols used in this book. Some of the symbols can have another meaning locally which will be defined in the text to avoid any confusion.

a_{\max}	Maximum value of $a(t)$	$F(t)$	External force applied to system
$a(t)$	Component of shock $\ddot{x}(t)$	F_{rms}	Rms value of force
A_c	Amplitude of compensation signal	F_m	Maximum value of $F(t)$
$A(\theta)$	Indicial admittance	g	Acceleration due to gravity
b	Parameter b of Basquin's relation $N \sigma^b = C$	h	Interval (f/f_0) or thickness of the target
c	Viscous damping constant	$h(t)$	Impulse response
C	Basquin's law constant ($N \sigma^b = C$)	H	Drop height
$d(t)$	Displacement associated with $a(t)$	H_R	Height of rebound
D	Diameter of programmer	$H(\)$	Transfer function
$D(f_0)$	Fatigue damage	i	$\sqrt{-1}$
e	Neper's number	IPS	Initial peak sawtooth
E	Young's modulus or energy of a shock	$\Im(\Omega)$	Imaginary part of $\ddot{X}(\Omega)$
ERS	Extreme response spectrum	k	Stiffness or coefficient of uncertainty
$E(t)$	Function characteristic of swept sine	K	Constant of proportionality of stress and deformation
f	Frequency of excitation	ℓ_{rms}	Rms value of $\ell(t)$
f_0	Natural frequency	ℓ_m	Maximum of $\ell(t)$
		$\ell(t)$	Generalized excitation (displacement)

$\dot{\ell}(t)$	First derivative of $\ell(t)$	$\dot{u}(t)$	First derivative of $u(t)$
$\ddot{\ell}(t)$	Second derivative of $\ell(t)$	$\ddot{u}(t)$	Second derivative of $u(t)$
L	Length	v_f	Velocity at end of shock
$L(\Omega)$	Fourier transform of $\ell(t)$	v_i	Impact velocity
m	Mass	v_R	Velocity of rebound
n	Number of cycles undergone by test-bar or material	$v(t)$	Velocity $\dot{x}(t)$ or velocity associated with $a(t)$
n_{FT}	Number of points of the Fourier transform	$V(\)$	Fourier transform of $v(t)$
N	Number of cycles to failure	x_m	Maximum value of $x(t)$
p	Laplace variable or percentage of amplitude of shock	$x(t)$	Absolute displacement of the base of a one-degree-of-freedom system
q_0	Value of $q(\theta)$ for $\theta = 0$	$\dot{x}(t)$	Absolute velocity of the base of a one-degree-of-freedom system
\dot{q}_0	Value of $\dot{q}(\theta)$ for $\theta = 0$	$\ddot{x}(t)$	Absolute acceleration of the base of a one-degree-of-freedom system
$q(\theta)$	Reduced response	\ddot{x}_{rms}	Rms value of $\ddot{x}(t)$
$\dot{q}(\theta)$	First derivative of $q(\theta)$	\ddot{x}_m	Maximum value of $\ddot{x}(t)$
$\ddot{q}(\theta)$	Second derivative of $q(\theta)$	\ddot{X}_m	Amplitude of Fourier transform $\ddot{X}(\Omega)$
Q	Q factor (quality factor)	$\ddot{X}(\Omega)$	Fourier transform of $\ddot{x}(t)$
$Q(p)$	Laplace transform of $q(\theta)$	$y(t)$	Absolute response of displacement of mass of a one-degree-of-freedom system
$r(t)$	Time window	$\dot{y}(t)$	Absolute response velocity of the mass of a one-degree-of-freedom system
R_e	Yield stress	$\ddot{y}(t)$	Absolute response acceleration of mass of a one-degree-of-freedom system
R_m	Ultimate tensile strength	z_m	Maximum value of $z(t)$
$R(\Omega)$	Fourier transform of the system response	z_s	Maximum static relative displacement
$\Re(\Omega)$	Real part of $\ddot{X}(\Omega)$	z_{sup}	Largest value of $z(t)$
s	Standard deviation		
S	Area		
SRS	Shock response spectrum		
STFT	Short term Fourier transform		
$S(\)$	Power spectral density		
t	Time		
t_d	Decay time to zero of shock		
t_i	Fall duration		
t_r	Rise time of shock		
t_R	Duration of rebound		
T	Vibration duration		
T_0	Natural period		
TPS	Terminal peak sawtooth		
$u(t)$	Generalized response		

$z(t)$	Relative response displacement of mass of a one-degree-of-freedom system with respect to its base	θ	Reduced time ($\omega_0 t$)
$\dot{z}(t)$	Relative response velocity	θ_d	Reduced decay time
$\ddot{z}(t)$	Relative response acceleration	θ_m	Reduced rise time
α	Coefficient of restitution	θ_0	Value of θ for $t = \tau$
δt	Temporal step	ρ	Density
$\delta(t)$	Dirac delta function	σ	Stress
ΔV	Velocity change	σ_{cr}	Crushing stress
ϕ	Dimensionless product $f_0 \tau$	σ_m	Maximum stress
$\phi(\Omega)$	Phase	τ	Shock duration
η	Damping factor of damped sinusoid	τ_1	Pre-shock duration
η_c	Relative damping of compensation signal	τ_2	Post-shock duration
$\lambda(\)$	Reduced excitation	τ_{rms}	Rms duration of a shock
$\Lambda(p)$	Laplace transform of $\lambda(\)$	ω_c	Pulsation of compensation signal
π	3.14159265...	ω_0	Natural pulsation ($2 \pi f_0$)
		Ω	Pulsation of excitation ($2 \pi f$)
		ξ	Damping factor

Table of Contents

Foreword to Series.	xiii
Introduction.	xvii
List of Symbols	xix
Chapter 1. Shock Analysis	1
1.1. Definitions	1
1.1.1. Shock	1
1.1.2. Transient signal	2
1.1.3. Jerk	3
1.1.4. Simple (or perfect) shock	3
1.1.5. Half-sine shock	3
1.1.6. Versed sine (or haversine) shock.	4
1.1.7. Terminal peak sawtooth (TPS) shock (or final peak sawtooth (FPS))	5
1.1.8. Initial peak sawtooth (IPS) shock	6
1.1.9. Square shock.	7
1.1.10. Trapezoidal shock.	8
1.1.11. Decaying sinusoidal pulse	8
1.1.12. Bump test.	9
1.1.13. Pyroshock	9
1.2. Analysis in the time domain	12
1.3. Temporal moments	12
1.4. Fourier transform	15
1.4.1. Definition	15
1.4.2. Reduced Fourier transform	17
1.4.3. Fourier transforms of simple shocks.	17
1.4.4. What represents the Fourier transform of a shock?	29

1.4.5. Importance of the Fourier transform	31
1.5. Energy spectrum	32
1.5.1. Energy according to frequency	32
1.5.2. Average energy spectrum	33
1.6. Practical calculations of the Fourier transform	33
1.6.1. General	33
1.6.2. Case: signal not yet digitized	33
1.6.3. Case: signal already digitized	36
1.6.4. Adding zeros to the shock signal before the calculation of its Fourier transform	37
1.6.5. Windowing	40
1.7. The interest of time-frequency analysis	41
1.7.1. Limit of the Fourier transform	41
1.7.2. Short term Fourier transform (STFT)	44
1.7.3. Wavelet transform	49
Chapter 2. Shock Response Spectrum	55
2.1. Main principles	55
2.2. Response of a linear one-degree-of-freedom system.	59
2.2.1. Shock defined by a force	59
2.2.2. Shock defined by an acceleration	60
2.2.3. Generalization	60
2.2.4. Response of a one-degree-of-freedom system to simple shocks	65
2.3. Definitions	69
2.3.1. Response spectrum	69
2.3.2. Absolute acceleration SRS	69
2.3.3. Relative displacement shock spectrum	70
2.3.4. Primary (or initial) positive SRS	70
2.3.5. Primary (or initial) negative SRS	70
2.3.6. Secondary (or residual) SRS	71
2.3.7. Positive (or maximum positive) SRS	71
2.3.8. Negative (or maximum negative) SRS	71
2.3.9. Maximax SRS	72
2.4. Standardized response spectra	73
2.4.1. Definition	73
2.4.2. Half-sine pulse	75
2.4.3. Versed sine pulse	76
2.4.4. Terminal peak sawtooth pulse	78
2.4.5. Initial peak sawtooth pulse	79
2.4.6. Square pulse	81
2.4.7. Trapezoidal pulse	81
2.5. Choice of the type of SRS	82

2.6. Comparison of the SRS of the usual simple shapes	83
2.7. SRS of a shock defined by an absolute displacement of the support . .	84
2.8. Influence of the amplitude and the duration of the shock on its SRS . .	84
2.9. Difference between SRS and extreme response spectrum (ERS)	86
2.10. Algorithms for calculation of the SRS	86
2.11. Subroutine for the calculation of the SRS	86
2.12. Choice of the sampling frequency of the signal	90
2.13. Example of use of the SRS	94
2.14. Use of SRS for the study of systems with several degrees of freedom	96
2.15. Damage boundary curve	100
Chapter 3. Properties of Shock Response Spectra	103
3.1. Shock response spectra domains	103
3.2. Properties of SRS at low frequencies	104
3.2.1. General properties	104
3.2.2. Shocks with zero velocity change	104
3.2.3. Shocks with $\Delta V = 0$ and $\Delta D \neq 0$ at the end of a pulse	115
3.2.4. Shocks with $\Delta V = 0$ and $\Delta D = 0$ at the end of a pulse	117
3.2.5. Notes on residual spectrum	120
3.3. Properties of SRS at high frequencies	121
3.4. Damping influence	124
3.5. Choice of damping	124
3.6. Choice of frequency range	127
3.7. Choice of the number of points and their distribution	128
3.8. Charts	131
3.9. Relation of SRS with Fourier spectrum	134
3.9.1. Primary SRS and Fourier transform	134
3.9.2. Residual SRS and Fourier transform	136
3.9.3. Comparison of the relative severity of several shocks using their Fourier spectra and their shock response spectra	139
3.10. Care to be taken in the calculation of the spectra	143
3.10.1. Main sources of errors	143
3.10.2. Influence of background noise of the measuring equipment	143
3.10.3. Influence of zero shift	145
3.11. Specific case of pyroshocks	152
3.11.1. Acquisition of the measurements	152
3.11.2. Examination of the signal before calculation of the SRS	154
3.11.3. Examination of the SRS	155
3.12. Pseudo-velocity shock spectrum.	156
3.12.1. Hunt's relationship	156
3.12.2. Interest of PVSS.	160
3.13. Use of the SRS for pyroshocks	162

3.14. Other propositions of spectra.	165
3.14.1. Pseudo-velocity calculated from the energy transmitted	165
3.14.2. Pseudo-velocity from the “input” energy at the end of a shock	165
3.14.3. Pseudo-velocity from the unit “input” energy	167
3.14.4. SRS of the “total” energy	167
Chapter 4. Development of Shock Test Specifications	175
4.1. Introduction.	175
4.2. Simplification of the measured signal	176
4.3. Use of shock response spectra.	178
4.3.1. Synthesis of spectra	178
4.3.2. Nature of the specification	180
4.3.3. Choice of shape	181
4.3.4. Amplitude	182
4.3.5. Duration	182
4.3.6. Difficulties.	186
4.4. Other methods	187
4.4.1. Use of a swept sine	188
4.4.2. Simulation of SRS using a fast swept sine	189
4.4.3. Simulation by modulated random noise.	193
4.4.4. Simulation of a shock using random vibration.	194
4.4.5. Least favorable response technique	195
4.4.6. Restitution of an SRS by a series of modulated sine pulses	196
4.5. Interest behind simulation of shocks on shaker using a shock spectrum	198
Chapter 5. Kinematics of Simple Shocks.	203
5.1. Introduction.	203
5.2. Half-sine pulse	203
5.2.1. General expressions of the shock motion	203
5.2.2. Impulse mode	206
5.2.3. Impact mode.	207
5.3. Versed sine pulse	216
5.4. Square pulse	218
5.5. Terminal peak sawtooth pulse	221
5.6. Initial peak sawtooth pulse	223
Chapter 6. Standard Shock Machines	225
6.1. Main types	225
6.2. Impact shock machines.	227
6.3. High impact shock machines	237
6.3.1. Lightweight high impact shock machine	237

6.3.2. Medium weight high impact shock machine	238
6.4. Pneumatic machines.	239
6.5. Specific testing facilities	241
6.6. Programmers	242
6.6.1. Half-sine pulse	242
6.6.2. TPS shock pulse.	250
6.6.3. Square pulse – trapezoidal pulse	258
6.6.4. Universal shock programmer	258
Chapter 7. Generation of Shocks Using Shakers	267
7.1. Principle behind the generation of a signal with a simple shape versus time	267
7.2. Main advantages of the generation of shock using shakers.	268
7.3. Limitations of electrodynamic shakers.	269
7.3.1. Mechanical limitations.	269
7.3.2. Electronic limitations	271
7.4. Remarks on the use of electrohydraulic shakers	271
7.5. Pre- and post-shocks	271
7.5.1. Requirements	271
7.5.2. Pre-shock or post-shock	273
7.5.3. Kinematics of the movement for symmetric pre- and post-shock. .	276
7.5.4. Kinematics of the movement for a pre-shock or a post-shock alone	286
7.5.5. Abacuses	288
7.5.6. Influence of the shape of pre- and post-pulses	289
7.5.7. Optimized pre- and post-shocks	292
7.6. Incidence of pre- and post-shocks on the quality of simulation	297
7.6.1. General	297
7.6.2. Influence of the pre- and post-shocks on the time history response of a one-degree-of-freedom system	297
7.6.3. Incidence on the shock response spectrum	300
Chapter 8. Control of a Shaker Using a Shock Response Spectrum	303
8.1. Principle of control using a shock response spectrum	303
8.1.1. Problems	303
8.1.2. Parallel filter method.	304
8.1.3. Current numerical methods	305
8.2. Decaying sinusoid	310
8.2.1. Definition	310
8.2.2. Response spectrum	311
8.2.3. Velocity and displacement	314
8.2.4. Constitution of the total signal	315
8.2.5. Methods of signal compensation	316