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# Kinematics and Dynamics of Machinery



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*There is no expedient to which a man will not resort to avoid the real labor of thinking.*

SIR JOSHUA REYNOLDS

It is the authors' sincere hope that users of this book will be encouraged to think and to explore designs and methods not explicitly described herein. Although worked out examples have been used extensively to illustrate applications to engineering problems, the intent is to build a capacity for solving new problems that one may encounter in the future.

*This book is dedicated to our parents.*

# Preface

Unlike some subjects, the theoretical concepts associated with kinematics and dynamics of machinery have immediate application to practical problems. As a result, most students of mechanical engineering have a great interest in mechanisms and machines. The authors have made extensive use of practical examples to maintain this interest while developing the analytical and graphical skills necessary to analyze linkages, cams, gears, and other mechanisms, and providing a foundation for the study of machine design.

Parts of this book are based on *Mechanism: Design-Oriented Kinematics*. The earlier book, which was well received in the United States and abroad, was heavily oriented toward applications and toward graphical techniques. While retaining these features, the new book has been almost entirely rewritten to reflect technological advances. Emphasis is now placed on analytical techniques suitable for machine calculations. In addition, two chapters on statics and dynamics of machines have been added.

Analytical vector methods and complex number methods are utilized for solving representative linkage problems. These methods are readily programmable, allowing analysis of a complete cycle of motion, using a computer or programmable calculator. Examples of machine calculations are given for specific problems. Program listings are not shown because the selection of a language will depend on the user's experience and the hardware and software available.

Graphical methods are also used extensively for linkage analysis. If a linkage is to be analyzed for a single position, construction of velocity and acceleration polygons provides a reasonably quick solution. An added advantage of the polygon method, utilizing the image principle, is that the polar plots so generated are an aid to visualizing linkage motion. When machine calculations are necessitated by the requirement that a linkage be studied over a wide range of motion, graphical methods may be used to spot-check machine results.

This book begins with basic concepts including linkage classification by motion characteristics, degrees-of-freedom of planar and spatial joints and linkages, limiting positions, transmission angle, and linkage interference. Modeling and computer graphics are illustrated. A number of mechanisms for specific applications are described including linkage combinations, fixed- and variable-speed power trains, industrial robots, and the rotating combustion engine. Both the international system of units (SI) and conventional English units are used.

Analytical vector methods, complex number methods, and graphical methods are described and applied to the displacement, velocity, and acceleration analysis of planar linkages. A spatial linkage is analyzed by analytical and graphical methods, and the synthesis of a function generator is described.

The design and analysis of cams is treated by graphical and analytical methods for various types of followers. The design and analysis of spur, helical, worm, and bevel gears is also treated, including shaft loading. Fixed- and variable-ratio gear trains, as well as other drive trains, are analyzed. Both the tabular and formula methods are applied to analysis of epicyclic trains.

Mechanisms are analyzed statically, and d'Alembert's principle is used to obtain

dynamic analyses. Graphical and analytical methods are used. Balancing of rotors and reciprocating machinery is treated as well.

For text use, most of the topics in this book may be covered in a three-credit-hour course given to undergraduate engineering students who have completed a course in statics and dynamics of rigid bodies. If more time is available, students may be challenged by emphasis on some of the more difficult topics, such as spatial linkages, synthesis, friction in mechanisms, balancing of multicylinder machines, and the theory of envelopes applied to cam design. Instructors will be able to select among a variety of methods demonstrated, according to their goals and preferences. For example, either analytical vector methods or complex number methods may be used as a basis for writing computer programs to solve planar linkages. However, if analysis of spatial linkages is to follow analysis of planar linkages, then vector methods might be used with both.

We wish to acknowledge the suggestions and comments of our students and colleagues at the New Jersey Institute of Technology and the University of North Dakota. In addition, we acknowledge the help of Ferdinand Freudenstein of Columbia University, Robert Williams of the CAD/CAM Systems Division of Control Data Corporation, Kenneth Waldron of Ohio State University, and William Park of Pennsylvania State University, who reviewed the entire manuscript and made many substantive suggestions. We are grateful for the help of our editors, Carl McNair and Cliff Robichaud. We note with deep regret the sad and untimely death in 1979 of our coauthor Walter Michels.

CHARLES E. WILSON  
J. PETER SADLER

# Symbols

Vectors shown in **boldface**, scalar magnitudes in lightface.

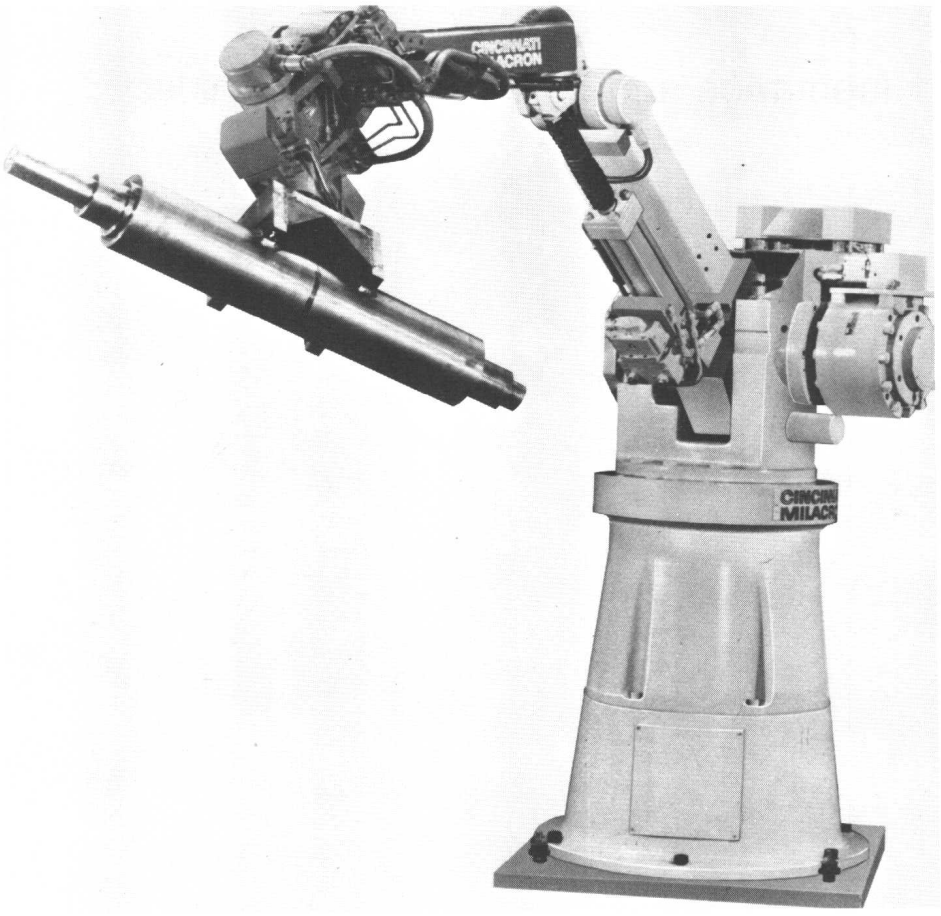
$\mathbf{A} \cdot \mathbf{B}$	Dot (scalar) product of vectors $\mathbf{A}$ and $\mathbf{B}$
$a$	Gear tooth addendum
$a, \mathbf{a}$	Acceleration
$a^c, \mathbf{a}^c$	Coriolis acceleration
$a^n, \mathbf{a}^n$	Normal acceleration
$a^t, \mathbf{a}^t$	Tangential acceleration
$\mathbf{bc}$	Velocity of $C$ relative to $B$ (velocity difference)
$C$	Cylinder pair; planet carrier
$\mathbf{C}$	Force couple
$\mathbf{C}_i$	Inertia couple or inertia torque
$c$	Center distance
CAD	Computer-aided design
$d$	Diameter of pitch circle
$d_b$	Diameter of base circle
$d_c$	Pitch diameter of equivalent spur gear
DF	Degrees-of-freedom
$e$	Instantaneous efficiency; cam-follower offset; piston offset; eccentricity
$e^{j\theta}$	Polar form of a complex number
$\mathbf{F}$	Force
$F_a$	Axial or thrust gear tooth force component
$F_e$	External force
$F_i$	Inertia force
$F_{ij}$	Force exerted by a member $i$ on member $j$
$F_n$	Normal gear tooth force
$F_r$	Radial gear tooth force component
$F_s$	Shaking force
$F_t$	Tangential gear tooth force component
$f_i$	Joint connectivity
$G$	Center of mass
$H$	Helix pair
$h$	Cam follower lift
$hp$	Horsepower
$I$	Mass moment of inertia
$j$	Cam follower jerk; $\sqrt{-1}$ , the imaginary unit used to represent quantities on the complex plane
$\mathbf{i}, \mathbf{j}, \mathbf{k}$	Cartesian unit vectors
$L$	Link length
$L_d$	Length of diagonal (of linkage polygon)
$l$	Lead of worm
$l_i$	Length of link $i$
$M_s$	Shaking moment



$m$	Mass; module; slope
$m^n$	Normal module
$N$	Number of gear teeth
$N$	Normal force
$N_f$	Formative number of gear teeth
$n$	Rotational speed (revolutions per minute)
$n_c$	Number of constraints
$n_l$	Number of links
$O_1$	Fixed bearing on link 1
$ob$	Absolute velocity of point $B$
$P$	Prism pair; planet gear; power; diametral pitch
$P$	Piston force
$P^n$	Normal diametral pitch
$p$	Transverse circular pitch
$p_b$	Base pitch
$p^n$	Normal circular pitch
$p_w$	Axial pitch of worm
$R$	Revolute pair; ring gear; length of crank
$R$	Position vector
$r$	Radius of pitch circle
$r$	Position vector; vector representing a link
$\dot{r}$	Derivative of $r$ with respect to time
$r^\circ$	Train value (speed ratio) for a planetary train relative to the carrier
$r_a$	Length of cam-follower arm; radius of addendum circle
$r_b$	Base circle radius; radius of back cone element
$r_c$	Center distance between cam and follower pivots; pitch radius of equivalent spur gear
$r_f$	Radius of cam-follower roller; radius of friction circle
$r_m$	Mean pitch radius
$r_v$	Velocity ratio
$r^u$	Unit vector
$r_x$	$x$ component of vector $r$
$S$	Sphere pair; sun gear
$s$	Displacement
$s$	Cam follower displacement
$\dot{s}$	Slider velocity
$s_n$	Axial spacing of engine cranks and cylinders
$T, T$	Torque
$T_e$	External torque
$t$	Time; gear tooth thickness
$v$	Velocity
$v_p$	Pitch line velocity
$W$	Work
$w$	Gear tooth width; weight
$x, y, z$	Cartesian coordinates
$\times$	Cross product
$\alpha, \alpha$	Angular acceleration
$\alpha$	Cam rotation angle; angle of approach
$\beta$	Angle of recess
$\Gamma$	Pitch angle

$\gamma$	Cam follower rotation; pitch angle
$\delta\phi, \delta x$	Virtual displacements
$\theta$	Angular position of link; cam angle; angle of action; connecting rod angle
$\theta_i$	Angular position of link $i$
$\theta_n$	Angular spacing of engine cylinders
$\lambda$	Lead angle of worm
$\mu$	Coefficient of sliding friction
$\rho$	Radius of curvature
$\rho_p$	Radius of curvature of pitch curve
$\Sigma$	Angle between shafts
$\phi$	Transmission angle; pressure angle; transverse pressure angle; friction angle
$\phi_i$	Angular position of link $i$
$\phi^n$	Normal pressure angle
$\psi$	Involute angle; helix angle
$\psi_n$	Angular spacing of engine cranks
$\omega, \omega$	Angular velocity

# Kinematics and Dynamics of Machinery



An industrial robot. SOURCE: Cincinnati Milacron.

# Index

- Acceleration
    - analytical solution based on acceleration polygon, 244–246
    - angular, 216
    - Coriolis, 219, 225, 249–254
    - image, 235–239
    - normal, 216–217, 219
    - of a point, 215
    - polygon, 227–246
    - relative, 220
    - tangential, 216–217, 219
  - Acceleration analysis, cam and follower, 299–319
  - Accuracy points, 117
  - Ackerman-type steering linkage, 62–64
  - ADAMS (automatic dynamic analysis of mechanical systems), 122–123, 547
  - Addendum
    - bevel gear, 440
    - spur gear, 359
  - Addendum circle, 359
  - Analytical cam design, 319–343
  - Angle of action, 376
  - Angle of approach, 377
  - Angle of recess, 377
  - Angular velocity ratio. *See* Speed ratio
  - Arc of action, 376
  - Articulated connecting rods, velocity analysis, 188–191
  - Axial gear force, 420, 436, 448
  - Axial pitch, 432
  - Backlash, 363
  - Balance of machinery, 609–632
    - dynamic, 612, 615
    - multicylinder engines, 622
    - reciprocating masses, 619
    - rotating masses, 610
    - rotors, 610
    - single-cylinder engines, 620
    - static, 612, 613
  - Ball-disk drives, 499–504
  - Barrel cam, 347
  - Base circle
    - cam, 284
    - gear, 366
  - Base circle radius
    - cams, 284
    - gears, 366
  - Base pitch, 378
  - Beam pump, velocity analysis, 185–186
  - Bearing force, 535, 540, 541, 553
  - Belt drives, 492–497
    - flat, 495–496
    - positive-drive, 496–497
    - variable speed, 493–495
    - v belts, 493–495
  - Bevel gears, 438–449
    - addendum, 440
    - addendum angle, 440
    - back cone, 440
    - back cone radius, 440
    - cone distance, 439
    - crown, 441
    - dedendum, 440
    - dedendum angle, 440
    - diametral pitch, 442
    - equivalent spur gear, 441
    - face angle, 440
    - face cone, 439
    - face width, 439
    - force analysis, 446
    - formative number of teeth, 442
    - hypoid, 446
    - internal, 441
    - miter, 441
    - pitch angle, 440
    - pitch cone, 439
    - pitch diameter, 440
    - pitch surface, 438
    - pressure angle, 439
    - root angle, 440
    - root cone, 440
    - shaft angle, 444
    - spiral, 445
    - spiral angle, 445
    - tooth size, 439
    - Tredgold's approximation, 441
    - velocity ratio, 442
    - Zerol, 446
  - Cams, 281–351. *See also* Follower motion, cams; Follower types, cams
    - analysis by centros, 203
    - analytical design, 319
    - barrel, 347
    - base circle, 284
    - computer-aided design and manufacturing (CAD/CAM), 319
    - conjugate, 345
    - constant-breadth, 344
    - curvature, 336
    - cusps, 337
    - cylindrical, 347
    - disk, 283
    - displacement diagram, 284, 286, 291, 294
    - dwelt, 284
    - end, 347
    - equivalent linkage, 176
    - face, 343
    - force analysis, 570
    - graphical acceleration analysis, 254–258
    - graphical layout, 283–299, 345–348
  - graphical velocity analysis, 174–176
  - jerk, 299
  - offset circle, 298
  - pitch circle, 290
  - pitch curve, 285
  - pitch point, 290
  - positive-motion, 343
  - pressure angle, 288, 329
  - prime circle, 290
  - production, 319, 350
  - profile, 284, 319
  - radius of curvature, 337
  - theory of envelopes, 319
  - three-dimensional, 347
  - trace point, 285
  - undercutting, 341
- Center distance
  - helical gears, 416, 427
  - spur gears, 369, 396
  - worm gearing, 433
- Centrifugal force, 584, 610
- Centros, 197–206
- Chace's method, 86
- Chain drives, 489–492
  - inverted tooth, 489–490
  - roller, 489
  - variable speed, 491–492
- Chebychev spacing, 117
- Circular pitch, 360, 411
- Clearance
  - cams, 344
  - spur gears, 360
- Clutches, 56, 58
  - sprag type, 56, 58
- Coefficient of friction, 561
- Complex numbers, 96–101
  - applied to acceleration analysis, 224–227
  - applied to displacement analysis, 99–101
  - applied to synthesis, 272–275
  - applied to velocity analysis, 142–143
  - differentiation, 97–98
  - division, 97–98
  - multiplication, 97–98
  - polar form, 97
  - rectangular form, 96
- Computer-aided design (CAD), 121–129, 319
- Computer-controlled industrial robots, 64–66
- Computer graphics, 28, 29, 319, 536
- Concurrency, point of, 537
- Cone roller-disk drives, 499
- Conjugate action of gears, 363
- Conjugate cam, 345
- Constant-breadth cam, 344
- Constraints, 10
- Contact length, gear teeth, 376

- Contact ratio, 377
- Coordinate systems
  - fixed, 135, 218
  - moving, 135–136, 218–219
- Coriolis acceleration, 219, 225, 249–254
- Coulomb friction, 561
- Counterweight, 611
- Couple, 533
- Coupler curves, 119–120
- Crank-rocker mechanism, 16–22
- Crankshaft torque, 540, 543, 551
- Crossed helical gears. *See* Helical gears
- Crossover position mechanism, 16–17, 19, 21–22
- Crown gear, 441
- Curvature of cams, 336
- Curved-wing air pump, 246–249, 594–597
- Cycle, 9
- Cycloidal gear, 366
- Cycloidal motion, 290, 305
- Cylindrical cam, 347
  
- d'Alembert's principle, 587
- Dedendum
  - bevel gear, 440
  - spur gear, 360
- Dedendum circle, 360
- Degrees-of-freedom, 10, 11, 13–15
- Diametral pitch, 360, 412, 442
- Differentials
  - bevel gear, 485–488
  - limited-slip, 488
  - planetary, 471–477
  - spur gear, 487–488
- Disk cam, 283
- Disk drives, 497–504
  - variable speed, 498
  - velocity analysis, 178
- Displacement analysis, 28, 29
  - analytical vector methods, 87–88
  - cam and follower motion, 299–319
  - complex number methods, 99–101
- Displacement diagram for cam follower, 284, 286, 291, 294
- Dot product, 83–84
- Double-enveloping worm gearset, 430
- Double-helical gear, 423
- Double-rocker mechanism, 16, 18–19, 21–22
- Double-threaded worm, 432
- Drafting instruments, 37–39
- Drag link mechanism, 16, 18, 21–22
- DRAM (dynamic response of articulated machinery), 123–124, 547
- Dwell of cam follower, 284
- Dynamically equivalent masses, 600
- Dynamic balance, rotors, 612, 615
- Dynamic force, 530, 584
- Dynamic-force analysis, 531, 584–632
- Dynamic-motion analysis, 586, 607
- Dynamics, 1, 10, 530, 584–632
- Dynamic unbalance, rotors, 612
  - by superposition, 535, 541, 557
  - by virtual work, 558
  - of worm gears, 436
- Four-bar linkage, 16–22
  - acceleration analysis, analytical vector methods, 221–224
  - acceleration analysis, graphical methods, 239–243
  - centros, 198–200
  - dynamic-force analysis of, 590
  - position analysis using the dot product, 91–96
  - position analysis using the vector cross product, 88–91
  - static-force analysis of, 541, 553
  - velocity analysis, analytical vector methods, 138–142
  - velocity analysis, graphical vector methods, 169–171
- Frame, 5
- Free-body diagrams, 534
- Freudenstein's method, 113–119
- Friction, 531, 560
- Friction angle, 562
- Friction circle, 563
- Friction coefficient. *See* Coefficient of friction
- Function generator, 112–119
- Fundamental law of gearing, 363
  
- Gears
  - bevel, 358, 438–449
  - helical, crossed, 358, 424–430
  - helical, parallel, 357, 408–424
  - manufacture of, 385, 420, 431
  - spur, 355–402
  - worm, 358, 430–438
- Gear trains, 50–51, 453. *See also* Planetary gear trains
  - double reductions, 456
  - reversing, 455
  - speed ratio change, 458
- Gear trains, dynamics of
  - forces, 396, 420, 436, 446, 520–522
  - torques, 397, 423, 437, 449, 520–523
  - transmitted power, 398, 423, 520–523
- Geneva mechanism, 101–102
- Graphical cam design, 283–299
- Grashof criterion, 16–22
- Grashof mechanism, 16–22
- Grübler's criterion, 15
  
- Helical gears, 408–430
  - center distance, 416, 427
  - circular pitch, transverse, 411
  - crossed, 424
  - diametral pitch, 412
  - double, 423
  - face width, 413
  - forces, 420
  - formative number of teeth, 418
  - hand, 408
  - helix angle, 411
  - herringbone gear, 423
  - manufacture, 420
  - module, 412
- Eccentric cam, 73–75, 326
- Eccentricity
  - cams, 290
  - rotors, 610
- Efficiency
  - of drive trains, 515
  - instantaneous, 564
- Engine, 8
  - balance, 619
- Equilibrium of forces and moments
  - dynamic-force analysis, 587
  - static-force analysis, 535, 548
- Equivalent inertia, 600
- Equivalent linkages, acceleration analysis, 246–249, 255–257
- Equivalent offset inertia force, 588
  
- Face cam, 343
- Face width, gear teeth, 359, 413, 439
- Flexible spline drive, 510–513
- Fluid links, 43, 44, 47
- Flywheel, 594, 608
- Follower motion, cams
  - constant acceleration and deceleration, 294, 307
  - cycloidal, 290, 305
  - modified uniform motion, 301
  - parabolic, 294, 307
  - polynomial, 314
  - simple harmonic, 286, 303
  - uniform motion or constant velocity, 283, 300
- Follower types, cams
  - conical, 347
  - knife-edge, 283
  - oblique flat-faced, 295
  - offset, 298, 327
  - oscillating, 296, 334
  - pivoted flat-faced, 296, 334
  - pivoted roller, 298, 336
  - primary, 298
  - radial, 283, 327
  - secondary, 298
  - spherical-faced, 296, 298
  - translating flat-faced, 290, 323, 337
  - translating roller, 286, 298, 327, 340
- Force, 531
  - centrifugal, 584, 610
  - dynamic, 530, 584
  - friction, 561
  - inertia, 530, 587
  - shaking, 610, 620
  - static, 530
- Force analysis
  - analytical methods of, 547–560
  - of bevel gears, 446
  - of cam and followers, 570
  - dynamic, 531, 584
  - of four-bar linkage, 541, 553, 590
  - with friction, 560–570
  - graphical methods of, 536–547
  - of helical gears, 420
  - by polygons, 537
  - of slider crank mechanism, 539, 551, 559, 563, 565, 597
  - of spur gears, 396
  - static, 530

- normal circular pitch, 411
- normal diametral pitch, 412
- normal module, 412
- normal pressure angle, 414
- parallel, 408
- pitch diameter, 412
- pitch surface, 411
- pressure angle, transverse, 414
- shaft angle, 425
- thrust load, 420
- Tredgold's approximation, 417
- velocity analysis, graphical, 180-181
- velocity ratio, 419, 428
- virtual number of teeth, 418
- Helical gear trains, 453
- Helix angle
  - helical gear, 411
  - worm gearing, 433
- Herringbone gear, 423
- Hypoid gears, 446
- Idler gear, 399, 454
- IMP (integrated mechanisms program), 122, 547
- Impulse drive, 51-53, 509-510
- Inertia force, 530, 587
  - balance of, 609
- Inertia torque or couple, 587
- Interchangeable gears, 381
- Interference, 36
  - gear teeth, 388
- Internal gears
  - bevel, 441
  - spur, 395
- International System of Units, 2
- Inverse method
  - acceleration analysis, 261-263
  - velocity analysis, 194-195
- Inversion, 9
- Inversion of a cam mechanism, 285, 319
- Involute function, 369
- Involute gear, 366
- Jerk analysis, cam and follower, 299-319
- Joint, 5. *See also* Pair
- Kennedy's theorem, 198
- Kinematic chain, 8
- Kinematics, 1, 10
- Lead, 432
- Lead angle, 433
- Length of action, gear teeth, 376
- Limiting positions, 25-27
  - acceleration analysis, 264-266
- Line of action, 371, 531
- Link, 3, 4
- Linkage, 9
  - displacement analysis by analytical vector methods, 87-88
  - four-bar, 16
  - planar, 9, 13
  - spatial, 9-11, 266-272
- Machine, 1, 8
- Mass moment of inertia, 586
- Mechanism, 1, 8. *See also* Four-bar linkage; Slider crank linkage; etc.
- Minimum radius of curvature, cams, 338, 341
- Miter gears, 441
- Modified uniform motion, cams, 301
- Module, 361, 412
- Moment of force, 532
- Moment of inertia. *See* Mass moment of inertia
- Motion
  - about a fixed axis, 133
  - analysis from dynamic characteristics, 586, 607
  - rectilinear, 73-75
- Multicylinder engine, balance of, 622
- Newton's second law, 585
- Newton's third law, 540
- Nonstandard spur gear, 394
- Normal circular pitch, 411
- Normal diametral pitch, 412
- Normal module, 412
- Normal pressure angle, 414
- Offset cam follower, 298, 327
- Operating pressure angle, 371
- Pair
  - cam, 7
  - cylinder, 6
  - helix, 6
  - kinematic, 5
  - lower and higher, 5
  - plane, 7
  - prism, 6
  - revolute, 6
  - sphere, 7
  - spur gear, 7
  - universal joint, 7
- Pantograph, 37-40
- Parabolic motion, 294, 307
- Parallel helical gears. *See* Helical gears
- Parameter studies, 157-161
- Period, 9
- Pinion, 359
- Pitch
  - axial, 432
  - circular, 360, 411, 432
  - diametral, 360, 412, 442
  - normal circular, 411
  - normal diametral, 412
- Pitch angle
  - bevel gear, 440
  - spur gear, 378
- Pitch circle
  - cam, 290
  - gear, 359
- Pitch cone, 439
- Pitch curve, 285
- Pitch diameter
  - bevel gear, 440
  - helical gear, 412
  - spur gear, 359
  - worm gearset, 433
- Pitch line velocity, 362
- Pitch point
  - cam, 290
  - gear, 363
- Pitch radius, 363
- Pitch surface, gears, 411, 438
- Planar motion, 9
- Planetary cone transmission, 507-509
- Planetary gears
  - acceleration, 518-519
  - velocity, 515-517
- Planetary gear trains, 463-484
  - balanced, 471
  - compound, 470-471
  - formula method for solving, 465-467
  - free-floating, 479-480
  - speed changing, 480-482
  - superposition, 467-484
  - tabular analysis, 467-484
  - tandem, 477-478
  - with more than one input, 482-484
- Planetary traction drives, 507-509
- Polycentric linkages, 18
- Polygon, force, 537
- Polynomial motion, 314
- Position analysis using the dot product, 91-96
- Position analysis using the vector cross product, 88-91
- Positive-motion cam, 343
  - conjugate cam, 345
  - constant-breadth cam, 344
  - cylindrical cam, 347
  - face cam, 343
- Power screws, 53, 55, 56
- Precision-drive considerations, 514
- Pressure angle
  - cams, 288, 329
  - gears, 371, 414, 439
- Pressure line, 371
- Primary balance
  - of forces, 624
  - of moments, 625
- Primary shaking force, 620
- Prime circle, cam, 290
- Quick return mechanism, 28-35
- Rack, 366, 414
- Radial cam follower, 283
- Radial gear force, 397, 420, 436, 448
- Radius of curvature
  - cam, 337
  - cam pitch curve, 341
  - spur gear tooth, 367
- Reaction force, 540
- RECSYN (synthesis with rectification), 124
- Resultant force, 532
- Resultant torque, 532
- Reverse-effective force, 587
- Reverse-effective torque, 587
- Ring gear. *See* Internal gears
- Rise of cam follower, 283
- Robots, 64-66
- Roller-torus drives, 505
- Root circle, 360

- Rosenauer's method of synthesis, 272-275
- Rotating combustion engine, 41, 43, 46
- Rotor, 584, 610
- Scalar product, 83-84
- Scotch yoke, 73-75
- graphical velocity analysis, 177
- Secondary balance
- of forces, 624
- of moments, 625
- Secondary shaking force, 620
- Self-locking gearset, 435
- Shaft angle
- bevel gears, 444
- crossed helical gears, 425
- Shaft torque, 397, 539, 541, 553
- Shaking couple, 612, 620
- Shaking force, 610, 620
- Shaking moment, 610
- Shaper mechanism
- centros, 205
- velocity analysis, 184-185
- Simple harmonic motion, 286, 303
- Single-cylinder engine
- balance of, 620
- force analysis, 539, 551, 597
- Single-enveloping worm gearset, 430
- Single-threaded worm, 432
- Slider crank linkage, 26-30, 41
- acceleration analysis, 227-235
- centros, 200-202
- displacement analysis, 87-88
- dynamic-force analysis, 597
- parameter studies, 157-161
- static-force analysis, 539, 551, 559, 563, 565
- velocity analysis, 227-235
- Sliding contact linkage
- acceleration analysis, complex number method, 224-227
- acceleration analysis, graphical methods, 249-253
- velocity analysis, complex number method, 142-146
- velocity analysis, graphical vector method, 171-173
- Sliding velocity
- between cam and follower, 573
- in crossed helical gears, 427
- in spur gears, 383
- Spatial linkages, 101-111
- acceleration analysis, 266-272
- displacement analysis by analytical methods, 104-110
- displacement analysis by graphical methods, 110-111
- four link, 103
- velocity analysis, 147-151
- Speed ratio
- bevel gears, 442
- cam and follower, 325
- crossed helical gears, 428
- parallel helical gears, 419
- spur gears, 363
- worm gearsets, 434
- Spiral bevel gear, 445
- Spur gears, 355-402
- addendum, 359
- addendum circle, 359
- angle of action, 376
- angle of approach, 377
- angle of recess, 377
- arc of action, 376
- backlash, 363
- base circle, 366
- base pitch, 378
- base radius, 366
- center distance, 369, 396
- centros, 204
- circular pitch, 360
- clearance, 360
- clearance circle, 360
- conjugate action, 363
- contact length, 376
- contact ratio, 377
- cycloidal tooth profile, 366
- dedendum, 360
- dedendum circle, 360
- diametral pitch, 360
- face width, 359
- force analysis, 396
- full-depth tooth, 381
- interchangeable, 381
- interference, 388
- interference point, 389
- internal, 395
- involute angle, 368
- involute function, 369
- involute tooth profile, 366
- length of action, 376
- line of action, 371
- long-and-short addendum teeth, 394
- manufacture, 385
- minimum teeth for pinion, 392
- module, 361
- nonstandard, 394
- operating pitch radius, 371
- operating pressure angle, 371
- pinion, 359
- pitch angle, 378
- pitch circle, 359
- pitch diameter, 359
- pitch line, rack, 386
- pitch line velocity, 362
- pitch point, 363
- pitch radius, 363
- pressure angle, 371
- pressure line, 371
- rack, 366
- sliding action, 383
- standard, 381
- stub tooth, 381, 393
- tooth face, 360
- tooth flank, 360
- tooth forces, 396
- tooth systems, 381
- tooth thickness, 360
- undercutting, 393
- velocity analysis, graphical, 178-180
- velocity ratio, 363
- whole depth, 360
- working depth, 360
- Spur gear trains, 453
- Standard gears, 381
- Static balance, rotors, 612, 613
- Static equilibrium, 535, 548
- Static force, 530
- Static-force analysis, 530-574
- Statics, 10, 530-574
- Static unbalance, rotors, 611
- Steering linkage, 62-64
- Straight-wing air pump, acceleration analysis, 254-255
- Stroke, cam follower, 285
- Superposition, 535, 541, 557
- Swash plate, 44-49
- Synthesis
- Freudenstein's method, 112-119
- Rosenauer's method, 272-275
- Tangential gear force, 397, 420, 436, 448
- Three-dimensional cams, 347
- Three-dimensional linkages. *See* Spatial linkages
- Three-force member, 537
- Throw, cam follower, 285
- Thrust load, gears
- bevel gears, 448
- helical gears, 420
- worm gears, 436
- Timing belt, 496
- Tooth forces
- bevel gears, 446
- helical gears, 420
- spur gears, 396
- worm gears, 436
- Torque, 531
- crankshaft, 540, 543, 551
- inertia, 587
- motor, 607
- shaft, 397, 539, 541, 553
- shaking, 610
- Trace point, 285
- Transaxle, 460
- Transmission angle, 22-25
- Transmissions, with axial shifting, 459-463
- Travel, cam follower, 285
- Tredgold's approximation
- bevel gears, 441
- helical gears, 417
- Trial solution method
- acceleration analysis, 263-265
- velocity analysis, 192-194
- Triple-rocker mechanism, 16, 18, 20-22
- Toggle linkage
- acceleration analysis, 258-261
- velocity analysis, 182-183
- Two-force member, 536
- Unbalance
- reciprocating, 610, 619
- rotating, 610
- Undercutting
- cams, 341
- gears, 393
- Uniform motion, cams, 283, 300
- Units, SI, 2
- Universal joints, 60-63



- Variable-stroke pump, 53–55
- Vector
  - addition, 76
  - components, 79
  - cross product, 80
  - differentiation, 84
  - equations, solution of, 85–86
  - subtraction, 77
  - unit, 79
- Velocity
  - angular, 133
  - image, 165–169
  - of a point, 132
  - polygon, 161–163
  - relative, 136–137
- Velocity analysis
  - analytical vector methods, 138–142
  - cam and follower, 299–319
  - graphical vector methods, 151–157, 161–197
- Velocity ratio. *See* Speed ratio
- Velocity-time studies, 195–196
- Virtual work, 558
- Wankel engine, 41, 43, 46
- Wave generator, 510–511
- Wheel-disk drives, 498
- Whole depth, gear teeth, 360
- Work, 558
- Working depth, gear teeth, 360
- Worm drives, 430, 454
- Worm gearing, 430–438
  - axial pitch, 432
  - center distance, 433
  - circular pitch, 432
  - double-enveloping, 430
  - forces, 436
  - helix angle, 433
  - irreversible, 435
  - lead, 432
  - lead angle, 433
  - manufacture, 431
  - pitch diameter of worm, 433
  - pitch diameter of worm gear, 433
  - single-enveloping, 430
  - velocity ratio, 434
- Zerol bevel gears, 446