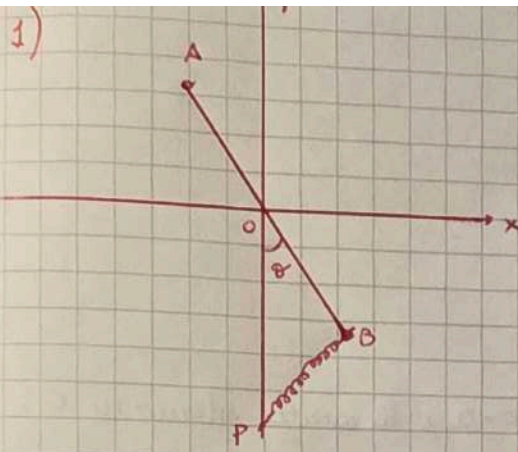


05/06/2024



$$\overline{AB} = 2l \quad \overline{AO} = \overline{OB}$$

$$m_A = m, \quad m_P = 3m$$

$$k = \frac{mg}{l}$$

$$q_1 = y_P = y, \quad q_2 = \vartheta$$

$$A = (-l \sin \vartheta, l \cos \vartheta)$$

$$B = (l \sin \vartheta, -l \cos \vartheta) \quad P = (0, y)$$

$$\omega = \dot{\vartheta} \Rightarrow v_A = \omega l = \dot{\vartheta} l \Rightarrow v_A^2 = \dot{\vartheta}^2 l^2$$

$$T_{\text{TOT}} = T_A + T_P = \frac{1}{2} m l^2 \dot{\vartheta}^2 + \frac{3}{2} m \dot{y}^2$$

$$|\overrightarrow{PB}|^2 = l^2 \sin^2 \vartheta + y^2 + l^2 \cos^2 \vartheta + 2ly \cos \vartheta = y^2 + l^2 + 2ly \cos \vartheta$$

$$V_{\text{TOT}} = mgl \cos \vartheta + 3mgy + \frac{mg}{2l} [y^2 + l^2 + 2ly \cos \vartheta]$$

$$L: T_{\text{TOT}} - V_{\text{TOT}} = \frac{1}{2} m l^2 \dot{\vartheta}^2 + \frac{3}{2} m \dot{y}^2 - mgl \cos \vartheta - 3mgy - \frac{mg}{2l} [y^2 + l^2 + 2ly \cos \vartheta]$$

$$\text{Equatione di Lagrange per } q_1 = y: \frac{d}{dt} \left(\frac{\partial L}{\partial \dot{y}} \right) - \frac{\partial L}{\partial y} = 0 \Rightarrow$$

$$\left. \begin{aligned} \frac{\partial L}{\partial \dot{y}} = 3m\dot{y} &\Rightarrow \frac{d}{dt} \left(\frac{\partial L}{\partial \dot{y}} \right) = 3m\ddot{y} \\ \frac{\partial L}{\partial y} = -3mg - \frac{mg}{l} y - mg \cos \vartheta \end{aligned} \right\} \Rightarrow 3m\ddot{y} + 3mg + \frac{mg}{l} y + mg \cos \vartheta = 0$$

$$\frac{\partial L}{\partial y} = -3mg - \frac{mg}{l} y - mg \cos \vartheta$$

$$\text{Equatione di Lagrange per } q_2 = \vartheta: \frac{d}{dt} \left(\frac{\partial L}{\partial \dot{\vartheta}} \right) - \frac{\partial L}{\partial \vartheta} = 0 \Rightarrow$$

$$\left. \begin{aligned} \frac{\partial L}{\partial \dot{\vartheta}} = m l^2 \dot{\vartheta} &\Rightarrow \frac{d}{dt} \left(\frac{\partial L}{\partial \dot{\vartheta}} \right) = m l^2 \ddot{\vartheta} \\ \frac{\partial L}{\partial \vartheta} = mgl \sin \vartheta + mgy \sin \vartheta \end{aligned} \right\} \Rightarrow m l^2 \ddot{\vartheta} - mg(l+y) \sin \vartheta = 0$$

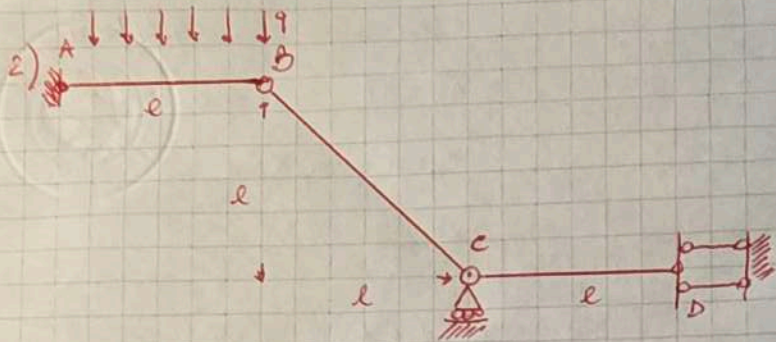
$$\frac{\partial L}{\partial \vartheta} = mgl \sin \vartheta + mgy \sin \vartheta$$

Per le configurazioni di equilibrio si ha:

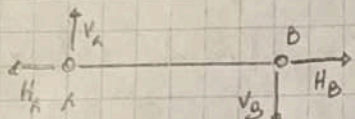
$$\left\{ \begin{aligned} \frac{\partial V}{\partial y} = 3mg + \frac{mg}{2l} [2y + 2l \cos \vartheta] &= 0 \\ \frac{\partial V}{\partial \vartheta} = -mgl \sin \vartheta - mgy \sin \vartheta &= 0 \end{aligned} \right. \Rightarrow$$

$$\left\{ \begin{aligned} y &= -l(3 + \cos \vartheta) \\ \sin \vartheta &= 0 \end{aligned} \right. \Rightarrow$$

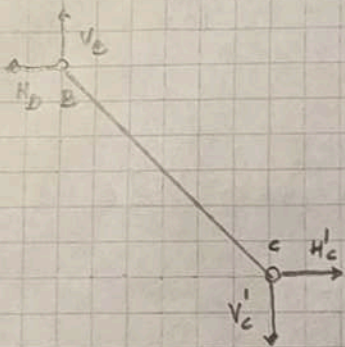
$$\left\{ \begin{aligned} \vartheta_1 &= -4l \\ \vartheta_2 &= \pi \end{aligned} \right. \quad \vee \quad \left\{ \begin{aligned} \vartheta_1 &= -2l \\ \vartheta_2 &= \pi \end{aligned} \right.$$



Prendiamo in considerazione le 3 strutture A-B, B-C, C-D e il carrello esterno in C:

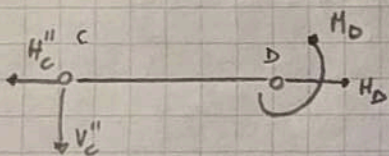


$$\text{pelo A: } \begin{cases} H_B - H_A = 0 \\ \bar{V}_A - \bar{V}_B - ql = 0 \\ (B-A) \times \underline{\Phi}_A + (H-A) \times q = 0 \end{cases} \Rightarrow \begin{cases} H_B = H_A \\ \bar{V}_A - \bar{V}_B = ql \\ -\bar{V}_B l - \frac{1}{2} ql^2 = 0 \end{cases}$$

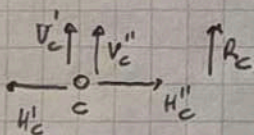


$$\text{pelo B: } \begin{cases} H'_C - H_B = 0 \\ V_B - V'_C = 0 \\ (C-B) \times \underline{\Phi}'_B = 0 \end{cases} \Rightarrow \begin{cases} H_B = H'_C \\ V_B = V'_C \\ (l \underline{i} - l \underline{j}) \times (H'_C \underline{i} - V'_C \underline{j}) = 0 \end{cases}$$

$$\begin{cases} H_B = H'_C \\ V_B = V'_C \\ H'_C = V'_C \end{cases}$$



$$\begin{cases} H_D - H''_C = 0 \\ V''_C = 0 \\ M_D = 0 \end{cases}$$



$$\begin{cases} H''_C = H'_C \\ V'_C + V''_C + R_C = 0 \end{cases}$$

Soluzioni:

$$\underline{\Phi}_A = \left(-\frac{1}{2} ql, \frac{1}{2} ql \right)$$

$$\underline{\Phi}_B = \left(-\frac{1}{2} ql, -\frac{1}{2} ql \right)$$

$$\underline{\Phi}'_C = \left(-\frac{1}{2} ql, -\frac{1}{2} ql \right)$$

$$\underline{\Phi}''_C = \left(-\frac{1}{2} ql, 0 \right)$$

$$\underline{\Phi}_D = \left(-\frac{1}{2} ql, 0 \right)$$

$$M_D = 0$$

$$\underline{R}_C = \left(0, \frac{1}{2} ql \right)$$