TABLE OF CONTENTS

Preface xiii

1 Introduction 1

1.1 **Engineering and Statics** 1

1.2 **A Brief History of Statics** 3
Galileo Galilei (1564–1642) 4
Isaac Newton (1643–1727) 4

1.3 **Fundamental Principles** 5
Newton's laws of motion 7

1.4 **Force** 8

1.5 **Units and Unit Conversions** 9
Dimensional homogeneity and unit conversions 9
Prefixes 10
Angular measure 11
Accuracy of calculations 12

1.6 **Newton's Law of Gravitation** 15
Relationship between specific weight and density 16

1.7 **Failure** 20

1.8 **Chapter Review** 22

2 Vectors: Force and Position 27

2.1 **Basic Concepts** 27
Introduction—force, position, vectors, and tides 27
Denoting vectors in figures 29
Basic vector operations 30
Performing vector operations 32
Resolution of a vector into vector components 33

2.2 **Cartesian Representation of Vectors in Two Dimensions** 44
Introduction—Cartesian representation and a walk to work 44
Unit vectors 44
Cartesian coordinate system 45
Cartesian vector representation 45
Addition of vectors using Cartesian components 47
Position vectors 48

2.3 **Cartesian Representation of Vectors in Three Dimensions** . . . 60
Right-hand Cartesian coordinate system 60
Cartesian vector representation 60

Direction angles and direction cosines 60
Position vectors 61
Use of position vectors to write expressions for force vectors 62
Some simple structural members 62

2.4 Vector Dot Product 76
Dot product using Cartesian components 77
Determination of the angle between two vectors 78
Determination of the component of a vector in a particular direction 78
Determination of the component of a vector perpendicular to a direction 79

2.5 Vector Cross Product 91
Cross product using Cartesian components 92
Evaluation of cross product using determinants 93
Determination of the normal direction to a plane 95
Determination of the area of a parallelogram 95
Scalar triple product 95

2.6 Chapter Review 104

3 Equilibrium of Particles 111

3.1 Equilibrium of Particles in Two Dimensions 111
Free body diagram (FBD) 112
Modeling and problem solving 116
Cables and bars 117
Pulleys 119
Reactions 120

3.2 Behavior of Cables, Bars, and Springs 135
Equilibrium geometry of a structure 135
Cables 135
Bars 136
Modeling idealizations and solution of $\sum \vec{F} = \vec{0}$ 136
Springs 136

3.3 Equilibrium of Particles in Three Dimensions 148
Reactions 148
Solution of algebraic equations 148
Summing forces in directions other than *x, y,* or *z* 150

3.4 Engineering Design 161
Objectives of design 161
Particle equilibrium design problems 162

3.5 Chapter Review 175

4 Moment of a Force and Equivalent Force Systems. 181

4.1 Moment of a Force 181
Scalar approach 182
Vector approach 183
Varignon's theorem 185
Which approach should I use: scalar or vector? 186

4.2 Moment of a Force About a Line 198
Vector approach 198
Scalar approach 199

4.3 Moment of a Couple 208
Vector approach 209
Scalar approach 209
Comments on the moment of a couple 209
Equivalent couples 210
Equivalent force systems 211
Resultant couple moment 211
Moments as free vectors 211

4.4 Equivalent Force Systems 221
Transmissibility of a force 221
Equivalent force systems 222
Some special force systems 224
Wrench equivalent force systems 225
Why are equivalent force systems called *equivalent*? 226

4.5 Chapter Review 238

5 Equilibrium of Bodies 245

5.1 Equations of Equilibrium 245

5.2 Equilibrium of Rigid Bodies in Two Dimensions 246
Reactions 246
Free body diagram (FBD) 248
Alternative equilibrium equations 250
Gears 251
Examples of correct FBDs 252
Examples of incorrect and/or incomplete FBDs 252

5.3 Equilibrium of Bodies in Two Dimensions—Additional Topics 270
Why are bodies assumed to be rigid? 270
Treatment of cables and pulleys 270
Springs 271
Superposition 272
Supports and fixity 273
Static determinacy and indeterminacy 274
Two-force and three-force members 276

5.4 Equilibrium of Bodies in Three Dimensions 292
Reactions 292
More on bearings 292
Scalar approach or vector approach? 294
Solution of algebraic equations 295
Examples of correct FBDs 295
Examples of incorrect and/or incomplete FBDs 297

5.5 Engineering Design 312
Codes and standards 314
Design problems 315

5.6 Chapter Review 321

6 Structural Analysis and Machines 329

6.1 Truss Structures and the Method of Joints 329
When may a structure be idealized as a truss? 331
Method of joints 331
Zero-force members 333
Typical truss members 335

6.2 Truss Structures and the Method of Sections 346
Treatment of forces that are not at joints 348
Static determinacy and indeterminacy 349
Design considerations 351

6.3 Trusses in Three Dimensions 363
Stability of space trusses and design considerations 364

6.4 Frames and Machines 372
Analysis procedure and free body diagrams (FBDs) 372
Examples of correct FBDs 373
Examples of incorrect and/or incomplete FBDs 375

6.5 Chapter Review 388

7 Centroids and Distributed Force Systems 395

7.1 Centroid 395
Introduction – center of gravity 395
Centroid of an area 397
Centroid of a line 397
Centroid of a volume 398
Unification of concepts 399
Which approach should I use: composite shapes or integration? 399
Finer points: surfaces and lines in three dimensions 400

7.2 Center of Mass and Center of Gravity 413
Center of mass 413
Center of gravity 414

7.3 Theorems of Pappus and Guldinus 425
Area of a surface of revolution 425
Volume of a solid of revolution 426
Proof of the Pappus–Guldinus theorems 426

7.4 Distributed Forces, Fluid and Gas Pressure Loading 432
Distributed forces 432
Distributed forces applied to beams 432
Fluid and gas pressure 433
Forces produced by fluids 435
Forces produced by gases 437

7.5 Chapter Review 450

8 Internal Forces 457

8.1 Internal Forces in Structural Members 457
Why are internal forces important? 457
Internal forces for slender members in two dimensions 458
Internal forces for slender members in three dimensions 459
Determination of internal forces 459

8.2 Internal Forces in Straight Beams 467
Determination of *V* and *M* using equilibrium 467
Shear and moment diagrams 467

8.3 Relations Among Shear, Moment, and Distributed Force . . . 478
Relations among *V, M,* and *w* 478
Determination of *V* and *M* using integration 479
Which approach should I use? 480
Tips and shortcuts for drawing shear and moment diagrams 481
Design considerations 482

8.4 Chapter Review 491

9 Friction 497

9.1 Basic Concepts 497
A brief history of tribology 497
A simple experiment 498
Coulomb's law of friction 499
Coefficients of friction 499
Dry contact versus liquid lubrication 501
Angle of friction 501
Problems with multiple contact surfaces 501
Wedges 502
Coulomb's law of friction in three dimensions 502
Design considerations 502

9.2 Problems with Multiple Contact Surfaces 513
Determination of sliding directions 513

9.3 Belts and Cables Contacting Cylindrical Surfaces 521
Equilibrium analysis 521

9.4 Chapter Review 529

10 Moments of Inertia 533

10.1 Area Moments of Inertia 533
An example—test scores 533
An example—beam loading 534
Definition of area moments of inertia 534
What are moments of inertia used for? 535
Radius of gyration 536
Evaluation of moments of inertia using integration 537

10.2 Parallel Axis Theorem 545
Use of parallel axis theorem in integration 546
Use of parallel axis theorem for composite shapes 546

10.3 Mass Moments of Inertia 553
An example–-figure skating 553
Definition of mass moments of inertia 553
What are mass moments of inertia used for? 554
Radius of gyration 555
Parallel axis theorem 555
Evaluation of moments of inertia using integration 556
Evaluation of moments of inertia using composite shapes 557

10.4 Chapter Review 572

A Technical Writing 579

B Answers to Selected Problems 583

Credits 585

Index 587