

The diagram shows a mechanical system with a central body (1) and two wheels (2) and (3). The wheels are connected to the body via springs and dampers. The wheels are labeled E and K. The body is labeled (1). The wheels are labeled (2) and (3). The diagram is labeled 'Example 4.4'.

```

% Define spring-damper constants
L_0 = 0.15; k = 10; d_c = 5; l_a = -2;
% Compute A matrices
A1 = A_matrix(phi1); A2 = A_matrix(phi2);
% Compute global components of s_A1 and s_A2
s_A1 = A1'*s_A1_local; s_B2 = A2'*s_B2_local;
% Compute global coordinates of points A1 and A2
r_A1 = r_Pos(s_A1); r_B2 = r_Pos(s_B2);
% Compute the spring force and damping force
d = r_B2 - r_A1; d_mag = norm(d); d_dir = d/d_mag;
f_sda = -k*(d_mag - L_0) + d_c*d_dot_mag*d_dir;
% Compute the spring moment
r_A1 = r_Pos(s_A1); r_B2 = r_Pos(s_B2);
r_A1 = r_Pos(s_A1); r_B2 = r_Pos(s_B2);
% Compute rotational transformation matrix
cp = cos(phi); sp = sin(phi);
A = [cp -sp; sp cp];

```

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Planar Multibody Dynamics Formulation Applications

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