

## THEORY OF MACHINE LAB –

### EXPERIMENT No-1

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|                       |                    |                 |                    |               |                 |
|-----------------------|--------------------|-----------------|--------------------|---------------|-----------------|
| 1.1 Objective         | 1.2 Apparatus used | 1.3 Theory      | 1.4 Observation    | 1.5 Procedure | 1.6 Calculation |
| 1.7 Result/Conclusion | 1.8 Precautions    | 1.9 Application | 2.1 Viva Questions |               |                 |

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**1.1 OBJECTIVE:** - To study various types of Kinematic links, pairs, chains and Mechanisms.

**1.2 Apparatus used :-** Modal base Apparatus

**1.3 Theory:-**

**Introduction:-** A machine consists of a number of parts or bodies. In this chapter, we shall study the mechanisms of the various parts or bodies from which the machine is assembled. This is done by making one of the parts as fixed, and the relative motion of other parts is determined with respect to the fixed parts.

**1.4 Kinematics Link or Element-**Each part of a machine, which moves relative to some other parts, is known as Kinematic link or element. A link may consist of several parts, which are rigidly fastened together, so that they do not move relative to one another. A link or element needs not to be a rigid body, but it must be a resistant body. A body is said to be a resistant body if it is capable of transmitting the required forces with negligible deformation. Thus a link should have the following two characteristics:

1. It should have relative motion.
2. It must be a resistant body.

**1.5 Types of Links**

In order to transmit motion, the driver and the follower may be connected by the following three types of links:

1. **Rigid link.** A Rigid link is one, which does not undergo any deformation while transmitting motion. Strictly speaking, rigid links do not exist. However, as the deformation of a connecting rod, crank etc. of a reciprocating steam engine is not appreciable, they can be considered as rigid links.
2. **Flexible link.** A flexible link is one, which is partly deformed in a manner not to affect the transmission of motion. For example, belt, ropes, chains and wires are flexible links and transmit tensile forces only.
3. **Fluid link.** A fluid link is one, which is formed by having a fluid in a receptacle, and the motion is transmitted through the fluid by pressure or compression only, as in the case of hydraulic presses, jacks and brakes.

**Structure:-**It is an assemblage of a number of resistant bodies (known as members) having no relative motion between them and meant for carrying loads having straining action. A railway bridge, a roof, truss, machine frames etc. are the example of a structure.

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**M Walker**



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web sep 12 2022 we developed a pattern of analyzing and setting up the solutions to problems involving newton s laws in newton s laws of motion in this chapter we continue to discuss these strategies and apply a step by step process

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web state newton s third law of motion identify the action and reaction forces in different situations apply newton s third law to define systems and solve problems of motion we have thus far considered force as a push or a pull however if you think about it you realize that no push or pull ever occurs by itself