

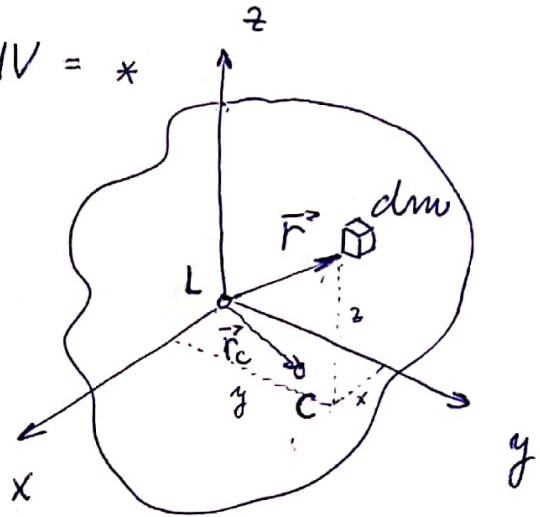
0-th order

- **mass** $m = \int_{(m)} dm = \int_{(V)} \rho \cdot dV = *$

dm ... elementary mass
 dV ... " volume

$dm = \rho \cdot dV$

if $\rho = \text{const.}$ $| * = \rho \cdot \int_{(V)} dV$
 (if) const



1-st order

\vec{r} ... displacement vector

STATIC MOMENT OF MASS

$\vec{S} = \int_{(m)} \vec{r} dm = \int_{(V)} \rho \vec{r} dV$

in component expression:

$S_{yz} = \int_{(m)} x dm$

$S_{zx} = \int_{(m)} y dm$

$S_{xy} = \int_{(m)} z dm$

(x, y, z) ... coordinates of displacement vector:

$\vec{r} = x\vec{i} + y\vec{j} + z\vec{k}$

calculation of center of mass:

$\vec{r}_c \cdot m = \int_{(m)} \vec{r} dm = \vec{S} \Rightarrow \vec{r}_c = \frac{\vec{S}}{m}$

$x_c = \frac{S_{yz}}{m}$; $y_c = \frac{S_{xz}}{m}$; $z_c = \frac{S_{xy}}{m}$

$\vec{r}_c = x_c\vec{i} + y_c\vec{j} + z_c\vec{k}$

2-nd order

(2)

MOMENTS OF INERTIA

a) With respect to the point
(origin of coordinates)

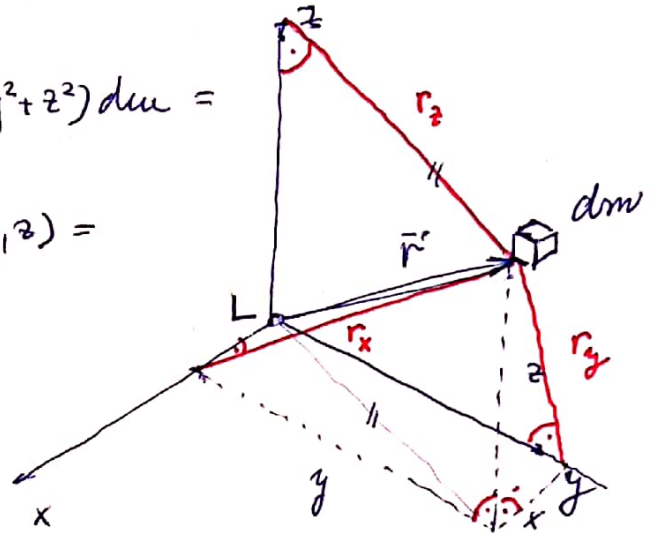
$$\vec{r} = x\vec{i} + y\vec{j} + z\vec{k}$$

$$J_L = \int_{(m)} (\vec{r})^2 dm = \int_{(m)} (x^2 + y^2 + z^2) dm =$$

$$(\vec{r})^2 = \vec{r} \cdot \vec{r} = (x, y, z) \cdot (x, y, z) = \\ = x^2 + y^2 + z^2$$

$$= \int_{(m)} (x^2 + y^2 + z^2) \rho dV$$

if $\rho = \text{const.}$ $J_L = \rho \int_{(m)} (x^2 + y^2 + z^2) dm$



b) With respect to the coordinate axis

$$J_x = \int_{(m)} r_x^2 dm \quad ; \quad r_x = \sqrt{y^2 + z^2}$$

$$J_x = \int_{(m)} (y^2 + z^2) dm$$

$$J_y = \int_{(m)} r_y^2 dm = \int_{(m)} (x^2 + z^2) dm$$

$$r_y = \sqrt{x^2 + z^2}$$

$$J_z = \int_{(m)} r_z^2 dm = \int_{(m)} (x^2 + y^2) dm$$

$$r_z = \sqrt{x^2 + y^2}$$

c) With respect to plane
(a plane of coordinate system)

$$J_{yz} = \int_{(u)} x^2 dm$$

$$J_{xz} = \int_{(u)} y^2 dm$$

$$J_{xy} = \int_{(u)} z^2 dm$$

Mutual associations :

$$J_L = \int_{(u)} (x^2 + y^2 + z^2) dm = \int_{(u)} x^2 dm + \int_{(u)} y^2 dm + \int_{(u)} z^2 dm = J_{yz} + J_{xz} + J_{xy}$$

$$J_x = \int_{(u)} (y^2 + z^2) dm = \int_{(u)} y^2 dm + \int_{(u)} z^2 dm = J_{xz} + J_{yx}$$

$$J_y = J_{xy} + J_{yz}$$

$$J_z = J_{xz} + J_{yz}$$

$$2J_L = J_x + J_y + J_z = \underline{J_{xz}} + \overline{J_{xy}} + \overline{J_{xy}} + \overline{J_{yz}} + \underline{J_{xz}} + \overline{J_{yz}}$$