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# Fondamenti di Meccanica e Biomeccanica del Movimento

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inviare commenti e suggerimenti a  
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**Errata Corrige e Ampliamenti**  
**3 luglio 2017**

Pagina	Riferimento	Errata	Corrige
xvi	riga 28	Gabriele Baronio	Stefano Uberti
27	Fig. 2.6	fascio muscolare	fibra muscolare
29	Fig. 2.9	$F=4 V=4 \Delta L= 1$	$F=4 V=1 \Delta L=1$
34	r.17 dal fondo	peso specifico	densità
51	fig. 2.33	*leggende scambiate*	
104	riga 4	<i>teorema di Galileo</i>	<i>teorema di Galileo</i>
135	eq. 3.4.31	$a_B = \dots + m\omega_2^2(\cos\theta + \sin\theta \tan\alpha) - \dots$	$a_B = \dots - m\omega_2^2(\cos\theta - \sin\theta \tan\alpha) - \dots$
141	eq. (3.5.6)	$\mathbf{P}_0 = \mathbf{t}_{(0)} + \mathbf{P}_{1(0)} = \mathbf{t}_{(0)} + \mathbf{R}_{01}\mathbf{P}_1$	$\mathbf{P}_0 = \mathbf{t}_{(0)} + \mathbf{P}_{1(0)} = \mathbf{t}_{(0)} + \mathbf{R}_{01}\mathbf{P}_1$
142	eq. (3.5.10)	$\mathbf{P}_2 = \mathbf{M}_{12}\mathbf{P}_2$	$\mathbf{P}_1 = \mathbf{M}_{12}\mathbf{P}_2$
158	es. 3.12	$\mathbf{v}_C = \begin{matrix} 0.06 \\ 0.77 \end{matrix} \text{ m/s}$	$\mathbf{v}_C = \begin{matrix} 0.16 \\ 0.94 \end{matrix} \text{ m/s}$
158	es. 3.12	$\mathbf{a}_C = \begin{matrix} -0.57 \\ 0.20 \end{matrix} \text{ m/s}^2$	$\mathbf{a}_C = \begin{matrix} -1.06 \\ 0.45 \end{matrix} \text{ m/s}^2$
215	Fig. 5.3	$l_{bs}$	$l_{cs}$
306	es. 6.12	$a = 7.4 \text{ m/s}^2$	$a = 3.7 \text{ m/s}^2$
339	eq. (8.4.23)	$\dots = c_1 e^{\omega_n(-\zeta + \sqrt{1-\zeta^2})t} + c_2 e^{\omega_n(-\zeta - \sqrt{1-\zeta^2})t}$	$\dots = c_1 e^{\omega_n(-\zeta + \sqrt{\zeta^2-1})t} + c_2 e^{\omega_n(-\zeta - \sqrt{\zeta^2-1})t}$
341	riga 10	$c = c_c r = \dots$	$c = c_{cr} = \dots$

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346	eq. (8.5.11)	$\begin{cases} A = C \sin \theta \\ B = C \cos \theta \end{cases}$	$\begin{cases} A = C \sin \alpha \\ B = C \cos \alpha \end{cases}$
347	riga 2	$f_a = 0.4$	$f_a = 0.6$
348	riga 5	$\dots = 11.05 \text{ N}$	$\dots = 265.62 \text{ N}$
349	riga 10	$\omega/\omega_n > 2$	$\omega/\omega_n > \sqrt{2}$
372	eq. (9.3.2)	$S_x = \dots \quad S_y = \dots$	$S_y = \dots \quad S_x = \dots$
376	righe 14, 16	$P$	$N$
386	eq. (9.7.5)	$\dots = -\frac{E}{\rho} S_y = 0 \rightarrow S_y = 0$	$\dots = -\frac{E}{\rho} S_z = 0 \rightarrow S_z = 0$
386	riga 7	in cui $S_y$ rappresenta ... all'asse $y$ ...	in cui $S_z$ rappresenta ... all'asse $z$ ...
433	Es. 11.1 riga 3	del braccio	dell'avambraccio
436	riga 4	§4.12	§4.2
438	riga 13	§4.12	§4.2
439	eq. (11.6.2)	$I_{xy} = \int \dots \simeq \sum \dots$	$I_{xy} = -\int \dots \simeq -\sum \dots$
439	eq. (11.6.2)	$I_{yz} = \int \dots \simeq \sum \dots$	$I_{yz} = -\int \dots \simeq -\sum \dots$
439	eq. (11.6.2)	$I_{xz} = \int \dots \simeq \sum \dots$	$I_{xz} = -\int \dots \simeq -\sum \dots$
487	eq. (12.9.1)	$\frac{\dot{i}}{d_1} - \frac{\dot{i}}{d_2}$	$\frac{\dot{i}}{d_1^2} - \frac{\dot{i}}{d_2^2}$
539	Fig. 13.43 asse $y$ fig. dx	$F_1 + F_2$	$F_2 + F_3$
545	eq. (13.3.6)	$\begin{cases} \dots -a_3 = 0 \\ \dots -a_4 = 0 \end{cases}$	$\begin{cases} \dots -a_4 = 0 \\ \dots -a_3 = 0 \end{cases}$
546	eq. (13.3.10)	$\begin{bmatrix} b_1 \dot{\vartheta}^2 C_\vartheta & b_2 \varepsilon_1^2 C_{\varepsilon_1} & b_3 \varepsilon_2^2 C_{\varepsilon_2} & -a_2 \varepsilon_3^2 C_{\varepsilon_3} \\ -b_1 \dot{\vartheta}^2 S_\vartheta & -b_2 \varepsilon_1^2 S_{\varepsilon_1} & -b_3 \varepsilon_2^2 S_{\varepsilon_2} & a_2 \varepsilon_3^2 S_{\varepsilon_3} \end{bmatrix}$	$\begin{bmatrix} b_1 C_\vartheta & b_2 C_{\varepsilon_1} & b_3 C_{\varepsilon_2} & -a_2 C_{\varepsilon_3} \\ -b_1 S_\vartheta & -b_2 S_{\varepsilon_1} & -b_3 S_{\varepsilon_2} & a_2 S_{\varepsilon_3} \end{bmatrix} \begin{bmatrix} \dot{\vartheta}^2 \\ \varepsilon_1^2 \\ \varepsilon_2^2 \\ \varepsilon_3^2 \end{bmatrix}$
547	eq. (13.3.11)	$= \mathbf{a}_{G_{cs}} - \dots$	$= \mathbf{a}_A - \dots$
547	eq. (13.3.11)	$(\mathbf{G}_{gm} - \mathbf{G}_{cs})$	$(\mathbf{G}_{gm} - \mathbf{A}) \quad (2 \text{ volte})$
547	eq. (13.3.11)	$= \mathbf{a}_{G_{em}} - \dots$	$= \mathbf{a}_B - \dots$
547	eq. (13.3.11)	$(\mathbf{G}_{pd} - \mathbf{G}_{gm})$	$(\mathbf{G}_{pd} - \mathbf{B}) \quad (2 \text{ volte})$
548	eq. (13.3.12)	$M_{cv} = \dots - f m_{pd} G_{pd y} C_{\varepsilon_2}$	$M_{cv} = \dots - f m_{pd} a_{G_{pd y}} C_{\varepsilon_2}$