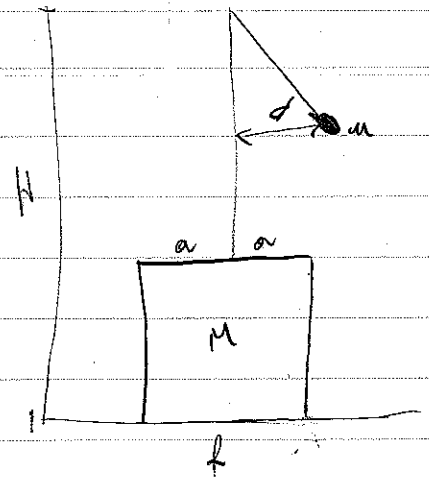


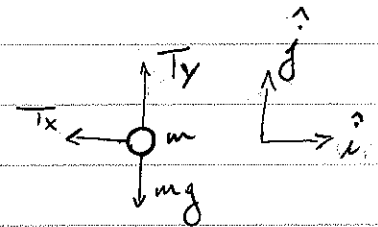
Ejercicio 1

La masa m describe un movimiento circular



a)

\hat{j}) $T_y = mg$ Porque el mov. es a altura cte.



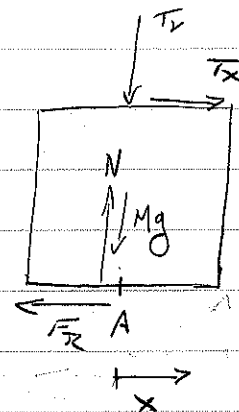
\hat{i}) $T_x = m \frac{v^2}{d}$

$\Rightarrow \vec{T} = m \frac{v^2}{d} \hat{i} + mg \hat{j}$

b)

\hat{j}) $N = (m+M)g$

\hat{i}) $T_x = F_R$



$F_R \leq \mu N$

$m \frac{v^2}{d} \leq (m+M)g\mu$

$v^2 < \frac{(m+M)gd}{\mu} \quad \text{Condición para no deslizar.}$

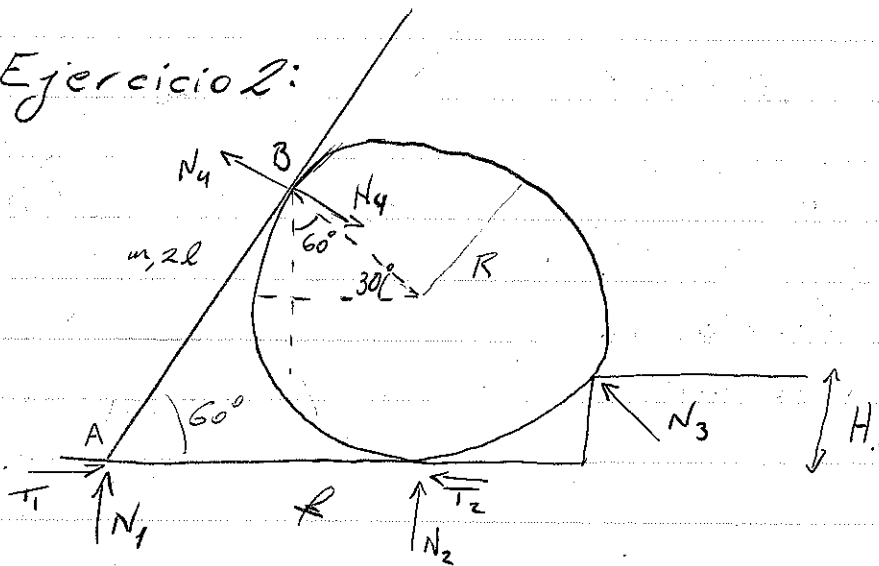
Torque en A:

$H T_x = N x$

$x = \frac{m v^2 H}{(m+M)gd} < a \Rightarrow v^2 < \frac{(m+M)gda}{m H}$

Condición de vuelco

Ejercicio 2:



La altura del punto B es $R + R \operatorname{sen}(30^\circ) = \frac{3}{2}R$

$$AB = \frac{\frac{3}{2}R}{\operatorname{sen}(60^\circ)} = \sqrt{3}R$$

Torque en A: $M_A = mgl \operatorname{sen}(30^\circ) - N_4 \sqrt{3}R = 0$
 $\Rightarrow N_4 = \frac{mgl}{2\sqrt{3}R}$

i) $T_1 = N_4 \cos(30^\circ) \Rightarrow T_1 = \frac{mgl}{4R}$

j) $N_1 - mg + N_4 \operatorname{sen}(30^\circ) = 0$

$$N_1 = mg \left(1 - \frac{l}{4\sqrt{3}R} \right)$$

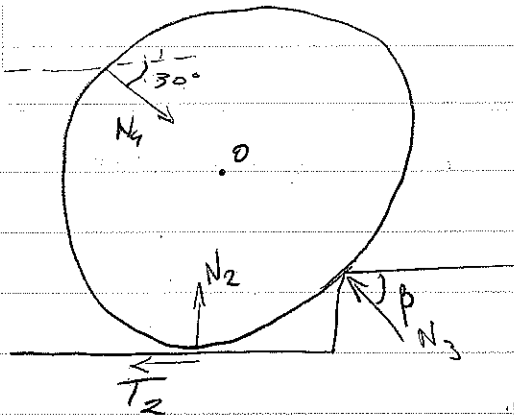
I) Condición para que la barra esté apoyada en el piso

$$N_1 > 0 \Rightarrow l < 4\sqrt{3}R$$

II) Condición de no deslizamiento

$$T_1 \leq \mu N_1 \Rightarrow \frac{\sqrt{3}l}{(4\sqrt{3}R - l)} \leq \mu$$

b)



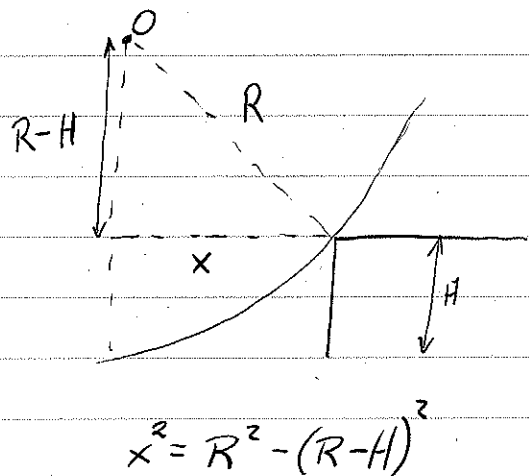
Ya que las fuerzas N_1 y N_3 son radiales

$$M_O = T_2 R = 0 \implies T_2 = 0$$

$$\begin{aligned} i) \quad N_1 \cos(30) - N_3 \cos \beta &= 0 \\ \implies N_3 &= \frac{mg}{4R \cos \beta} \end{aligned}$$

$$\begin{aligned} j) \quad N_1 \sin(30) - N_3 \sin \beta - N_2 &= 0 \\ \implies N_2 &= \frac{mg}{4\sqrt{3}R} - \frac{mg}{4R} \tan \beta \end{aligned}$$

$$\begin{aligned} \tan \beta &= \frac{op}{ad} = \frac{R-H}{(R^2 - (R-H)^2)^{1/2}} \\ &= \frac{R-H}{(2RH - H^2)^{1/2}} \end{aligned}$$



Condición $N_2 \geq 0$

$$\implies \left(\frac{1}{\sqrt{3}} - \tan \beta \right) \geq 0 \implies \frac{(2RH - H^2)}{3} \geq (R-H)^2$$

$$\implies 0 \geq \left(H - \frac{3R}{2} \right) \left(H - \frac{R}{2} \right) \implies \frac{R}{2} \leq H$$

sin sentido Físico