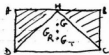


$$1) mR = 2m \quad mT = m$$

$$HG = \frac{1}{m} \left( 2m \cdot \frac{l}{2} - m \cdot \frac{2}{3} l \right) = \frac{l}{3}$$



$$\frac{I_G^R}{G_R} = mL^2 \left( \frac{1}{6}, \frac{2}{3}, \frac{5}{6} \right)$$

$$\frac{I_G^R}{G} = \frac{I_G^R}{G_R} + mL^2 \left( \frac{1}{18}, 0, \frac{1}{18} \right) = mL^2 \left( \frac{2}{9}, \frac{2}{3}, \frac{8}{9} \right)$$

$$\frac{I_G^T}{G_T} = mL^2 \left( \frac{1}{18}, \frac{1}{6}, \frac{2}{9} \right)$$

$$\frac{I_G^T}{G} = \frac{I_G^T}{G_T} + mL^2 \left( \frac{1}{9}, 0, \frac{1}{9} \right) = mL^2 \left( \frac{1}{6}, \frac{1}{6}, \frac{1}{3} \right)$$

$$\frac{I_G^L}{G} = \frac{I_G^R}{G} - \frac{I_G^T}{G} = mL^2 \left( \frac{1}{18}, \frac{1}{2}, \frac{5}{9} \right)$$

$$2) \bar{X}_G = (s+l) \bar{e}_1 + \frac{l}{3} \sin \theta \bar{e}_2 - \frac{l}{3} \cos \theta \bar{e}_3$$

$$\dot{\bar{V}}_G = \dot{s} \bar{e}_1 + \frac{l}{3} \cos \theta \dot{\theta} \bar{e}_2 + \frac{l}{3} \sin \theta \dot{\theta} \bar{e}_3 \quad \dot{V}_G^2 = \dot{s}^2 + \frac{l^2}{9} \dot{\theta}^2$$

$$\bar{\omega} = \dot{\theta} \bar{k}_1 \quad \bar{\omega} \cdot \frac{I_G(\bar{\omega})}{G} = I_{G11} \dot{\theta}^2$$

$$T = \frac{1}{2} m \dot{V}_G^2 + \frac{1}{2} I_{G11} \dot{\theta}^2 = \frac{1}{2} m (\dot{s}^2 + \frac{l^2}{9} \dot{\theta}^2) + \frac{1}{2} \frac{m l^2}{18} \dot{\theta}^2 = \frac{1}{2} m (\dot{s}^2 + \frac{1}{6} l^2 \dot{\theta}^2)$$

$$V = \frac{k}{2} (D-s)^2 + mgy z_G - \bar{F} \cdot \bar{X}_G = \frac{k}{2} (s^2 + l^2) - \frac{mgl}{3} \cos \theta - F(x_C + y_C) = \frac{k}{2} s^2 - \frac{mgl}{3} \cos \theta - \frac{mgl}{3} (s \sin \theta) + \text{const.}$$

$$L = T - V = \frac{m}{2} (\dot{s}^2 + \frac{1}{6} l^2 \dot{\theta}^2) - \frac{k}{2} s^2 + \frac{mgl}{3} (\cos \theta + \sin \theta + s)$$

$$m\ddot{s} + ks - \frac{mgl}{3} = 0$$

$$\frac{1}{6} m l^2 \ddot{\theta} + \frac{mgl}{3} (\sin \theta - \cos \theta) = 0$$

$$3) V_s = ks - \frac{mgl}{3} = 0$$

$$s = \frac{mgl}{3k}$$

$$V_\theta = \frac{mgl}{3} (\sin \theta - \cos \theta) = 0$$

$$\tan \theta = 1$$

$$\theta = \frac{\pi}{4}, \frac{5\pi}{4}$$

$$V_{ss} = k > 0 \quad V_{\theta\theta} = \frac{mgl}{3} (\sin \theta + \cos \theta) \quad V_{s\theta} = 0$$

$$V_{\theta\theta} > 0 \quad \text{für } \theta = \frac{\pi}{4} \quad (\text{stabil})$$

$$V_{\theta\theta} < 0 \quad \text{für } \theta = \frac{5\pi}{4} \quad (\text{instabil})$$

$$4) \bar{\phi}_A + \bar{\phi}_B + m\bar{g} - k(D-s) + \bar{F} = 0$$

$$(B-A) \wedge \bar{\phi}_B + (G-A) \wedge m\bar{g} - k(D-s) \wedge (D-s) + (C-A) \wedge \bar{F} = 0$$

$$\bar{\phi}_A + \bar{d}_A - mgy \bar{e}_3 - k \left( \frac{mgl}{3k} \bar{e}_1 + \frac{\sqrt{2}}{2} l \bar{e}_2 - \frac{\sqrt{2}}{2} l \bar{e}_3 \right) + \frac{mgl}{3} (\bar{d}_1 + \bar{e}_2) = 0$$

$$2l \bar{e}_1 \wedge \bar{\phi}_B + (l \bar{e}_1 + \frac{\sqrt{2}}{6} l \bar{e}_2 - \frac{\sqrt{2}}{6} l \bar{e}_3) \wedge (-mgy \bar{e}_3) - k l \frac{\sqrt{2}}{2} (\bar{e}_2 - \bar{e}_3) \wedge (s \bar{e}_1 + \frac{\sqrt{2}}{2} l \bar{e}_2 - \frac{\sqrt{2}}{2} l \bar{e}_3) + (2l \bar{e}_1 + \frac{\sqrt{2}}{2} l \bar{e}_2 - \frac{\sqrt{2}}{2} l \bar{e}_3) \wedge \frac{mgl}{3} (\bar{e}_1 + \bar{e}_2) =$$

$$= 2l \bar{e}_1 \wedge \bar{\phi}_B + mgy \bar{e}_3 \wedge (\bar{e}_2 - \frac{\sqrt{2}}{2} \bar{e}_3) + \frac{mgl}{3} \frac{2}{3} l (\bar{e}_2 + \bar{e}_3) + \frac{mgl}{3} [2l \bar{e}_3 + \frac{\sqrt{2}}{2} l (-\bar{e}_2 - \bar{e}_1 + \bar{e}_1)] = 0$$

$$\phi_{B2} = -\frac{mgy}{3}$$

$$\phi_{B3} = \frac{mgy}{2}$$

$$\phi_{A2} = -\frac{mgy}{3} + \frac{l}{2} k l$$

$$\phi_{A3} = \frac{mgy}{2} - \frac{\sqrt{2}}{2} k l$$