Intro Physics Semester I **Name:**

Homework 10: Rotational Kinematics: One or two full answer questions will be marked. There will also be a mark for completeness. Homeworks are due usually the day after the chapter they are for is finished. Solutions will be posted soon thereafter. The solutions are intended to be (but not necessarily are) super-perfect and often go beyond a fully correct answer.

Answer Table

Name:

	a	b	c	d	e		a	b	c	d	e
1.	O	O	O	O	O	31.	O	O	O	O	O
2.	O	O	O	O	O	32.	O	O	O	O	O
3.	O	O	O	O	O	33.	O	O	O	O	O
4.	O	O	O	O	O	34.	O	O	O	O	O
5.	O	O	O	O	O	35.	O	O	O	O	O
6.	O	O	O	O	O	36.	O	O	O	O	O
7.	O	O	O	O	O	37.	O	O	O	O	O
8.	O	O	O	O	O	38.	O	O	O	O	O
9.	O	O	O	O	O	39.	O	O	O	O	O
10.	O	O	O	O	O	40.	O	O	O	O	O
11.	O	O	O	O	O	41.	O	O	O	O	O
12.	O	O	O	O	O	42.	O	O	O	O	O
13.	O	O	O	O	O	43.	O	O	O	O	O
14.	O	O	O	O	O	44.	O	O	O	O	O
15.	O	O	O	O	O	45.	O	O	O	O	O
16.	O	O	O	O	O	46.	O	O	O	O	O
17.	O	O	O	O	O	47.	O	O	O	O	O
18.	O	O	O	O	O	48.	O	O	O	O	O
19.	O	O	O	O	O	49.	O	O	O	O	O
20.	O	O	O	O	O	50.	O	O	O	O	O
21.	O	O	O	O	O	51.	O	O	O	O	O
22.	O	O	O	O	O	52.	O	O	O	O	O
23.	O	O	O	O	O	53.	O	O	O	O	O
24.	O	O	O	O	O	54.	O	O	O	O	O
25.	O	O	O	O	O	55.	O	O	O	O	O
26.	O	O	O	O	O	56.	O	O	O	O	O
27.	O	O	O	O	O	57.	O	O	O	O	O
28.	O	O	O	O	O	58.	O	O	O	O	O
29.	O	O	O	O	O	59.	O	O	O	O	O
30.	O	O	O	O	O	60.	O	O	O	O	O

1. A circle can be divided into:

   a) 360 divisions only. b) any number of divisions you like. c) 2π divisions only.
   d) π divisions only. e) 360 or 2π divisions only.

2. How many radians are there in a circle?

   a) π. b) 2π. c) 3π. d) $360°$. e) 360.

3. The division of the circle into 360° was an arbitrary choice—and we don't know why. We just know the ancient Mesopotamian mathematicians and astronomers did it this way—you know Mesopotamia—ancient Iraq: "the cradle of civilization". Their choice was just adopted by the ancient Greeks and got passed on to us. In the French Revolutionary epoch, the decimal system was adopted for most measures, but the revolutionaries didn't get around (you might say) to the circle. We can guess that one reasons is that the ancient Mesopotamians had a preference for whole number arithmetic particularly in division and 360 has a lot of whole number factors. How many whole number (i.e., integer) factors does 360 have counting 1 and 360 itself?

   a) 24. b) 360. c) 6. d) 7. e) 12.

4. What is the approximate conversion factor from radians to degrees?

   a) 1/60 degrees/radian. b) π degrees/radian. c) 2π degrees/radian.
   d) 60 degrees/radian. e) 360 degrees/radian.

5. There are 2π radians in a circle. It's rather inconvenient that this means that there are $2\pi = 6.2831853\ldots$ radians in a circle which is an irrational number. For convenience, we could use the revolution (with sympbol Rev: vocalized rev) as a new unit: $1\,\text{Rev} = 2\pi$. One hundredth of an Rv would be a:

   a) exaRev. b) megaRev. c) kiloRev. d) deciRev. e) centiRev.

6. Approximately, at arm's length a finger subtends 1°, a fist 10°, and a spread hand 18°. These numbers, of course, vary a bit depending on person and exactly how the operation is done. What are these angles approximately in radians?

   a) 1/60, 1/6, and 1/3 radians. b) 60, 600, and 1800 radians.
   c) $\pi/12$, $\pi/3$, and $\pi/2$ radians. d) $\pi/12$, $\pi/3$, and π radians. e) $\pi/12$, $\pi/3$, and 2π radians.

7. Can you cover the Moon with your finger held at arm's length? **HINT:** You could try for yourself if you are not in a a test *mise en scène*.

   a) No. The Moon is much larger in angle than a finger. Just think how huge the Moon looks on the horizon sometimes.
   b) It depends critically on the size of one's finger and arm. People with huge hands can to it and those without can't.
   c) Yes. A finger at arm's length typically subtends about 10° and the Moon subtends 0.01°.
   d) No. The Moon's diameter is about 3470 km and a finger is about a centimeter or so in width.
   e) Usually yes. A finger at arm's length typically subtends about 1° and the Moon subtends 0.5°.

8. For small angles θ measured in radians and with increasing accuracy as θ goes to zero (where the formulas are in fact exact), one has the small angle approximations:

   a) $\sin\theta \approx \cos\theta \approx 1 - \frac{1}{2}\theta^2$. b) $\cos\theta \approx \tan\theta \approx 1 - \frac{1}{2}\theta^2$. c) $\sin\theta \approx \cos\theta \approx \theta$.
   d) $\cos\theta \approx \tan\theta \approx \theta$. e) $\sin\theta \approx \tan\theta \approx \theta$.

9. "Let's play *Jeopardy*! For \$100, the answer is: It is the study of the description of rotational motion or angular motion without reference to forces or torques."

   What is ____________, Alex?

   a) translational dynamics b) rotational dynamics c) translational kinematics
   d) rotational kinematics e) rotational freight

10. The rotational kinematics analog to 1-dimensional translational (or rectilinear) motion is:

    a) general rotation. b) kernal rotation. c) rotation about a single fixed axis.
    d) rotation about two axes. e) rotation about three axes.

11. A change in angular position of a point is a/an:

    a) angular displacement. b) angular velocity. c) angular acceleration.
    d) translational velocity. e) translational acceleration.

12. The usual symbols for the angular kinematic variables angular displacement, angular velocity, and angular acceleration all for rotational motion around a single fixed axis are, respectively:

    a) α, β, γ. b) θ, ω, α. c) θ, α, ω. d) ω, θ, α. e) δ, ϵ, ζ.

13. About a single fixed axis,

$$\omega = \lim_{\Delta t \to 0} \frac{\Delta\theta}{\Delta t} \qquad \text{or, if you know calculus,} \qquad \omega = \frac{d\theta}{dt}$$

    is the definition of:

    a) angular displacement. b) angular acceleration. c) angular velocity.
    d) angular momentum. e) torque.

14. About a single fixed axis,

$$\alpha = \lim_{\Delta t \to 0} \frac{\Delta\omega}{\Delta t} \qquad \text{or, if you know calculus,} \qquad \alpha = \frac{d\omega}{dt}$$

    is the definition of

    a) angular displacement. b) angular acceleration. c) angular velocity.
    d) angular momentum. e) torque.

15. The formulas

$$\Delta s = \Delta\theta r \ , \qquad v = \omega r \ , \qquad a = \alpha r$$

    (where r is the radius of circular motion) relate the rotational variables to the analog:

    a) units. b) transgressional variables. c) tangential variables. d) angular units.
    e) translational units.

16. The rotational constant-angular-acceleration kinematic equations:

    a) have no resemblance to the linear kinematic equations.
    b) are exactly the same as the linear kinematic equations, except that the angular kinematic equations relate **ANGULAR** rather than linear variables.
    c) are exactly the same as the linear kinematic equations, except that the angular kinematic equations relate **LINEAR** rather than angular variables.
    d) do not allow for angular acceleration.
    e) include torque terms.

17. The number of **ALGEBRAICALLY INDEPENDENT** rotational constant-angular-acceleration equations is:

    a) 5. b) 4. c) 3. d) 2. e) 1.

18. The rotational constant-angular-acceleration equation

$$\omega^2 = \omega_0^2 + 2\alpha\Delta\theta$$

    by itself alone does **NEVER** allows you to solve for:

    a) α. b) $\Delta\theta$. c) ω_0. d) ω. e) t.

19. A wheel spins π radians in 10.0 s with an angular acceleration of 4.00 radians/s^2. What is its final angular velocity?

    a) 80.1 radians/s. b) 203 radians/s. c) 20.3 radians/s. d) 3.14 radians/s.
    e) 6.28 radians/s.

20. A discus thrower (in Greek, a *Diskobolos*) accelerates a discus from rest through π radians accelerating it from angular velocity 0 to angular velocity 15 rad/s. We idealize his motion as circular with radius

$r = 0.81\,\mathrm{m}$. The time of the throwing motion is $0.27\,\mathrm{s}$. What is the net **TRANSLATIONAL** acceleration (not tangential acceleration) of the discus at the end of the throwing motion just before release? Give the direction of acceleration relative to the inward radial direction.

a) $200\,\mathrm{m/s^2}$; $10°$. b) $13.9\,\mathrm{m/s^2}$; $188°$. c) $188\,\mathrm{m/s^2}$; $13.9°$. d) $150\,\mathrm{m/s^2}$; $15°$.
e) $100\,\mathrm{m/s^2}$; $50°$.

21. Waldo's back—you know, Waldo Pepper, the Playful Pig—just accept it. This time, the Bold Boar has decided to become an astronaut and is training on NASA's giant centrifuge—the one in the film *The Right Stuff*. Let's guess it has a radius of $10\,\mathrm{m}$. The centrifuge spins in the horizontal: i.e., the centrifuge axis is perpendicular to the ground.

    a) Starting from rest the centrifuge goes into a constant angular acceleration phase for $10\,\mathrm{s}$. At this point Waldo—who does indeed have a mass of $150\,\mathrm{kg}$—notes that the vertical weighing scale he is nauseatingly pressed on reads $3000\,\mathrm{N}$. What is the centripetal force on Waldo and what kind of force is the centripetal force?

    b) The Sentient Swine now does some math—some correct math. What does Waldo find for his tangential velocity at the $10\,\mathrm{s}$ mark? What does he find for his angular velocity at the $10\,\mathrm{s}$ mark?

    c) Doing a little more correct math, Waldo now finds his angular acceleration from time zero to the $10\,\mathrm{s}$ mark. What is this angular acceleration?

    d) At this point, the Shaken Bacon does a little Gedanken experiment—just like Einstein—"what if I instantaneously left NASA's big blender and found myself 1000 **KILOMETERS** from the center of Pluto (formerly the 9th planet) and moving perpendicularly to the line to Pluto in free space, but with my current velocity?" What in this case would Waldo's angular velocity be about Pluto—for an instant since after that the Heck-of-a-Hog knows his orbital path will almost certainly not be circular.

Equation Sheet for Introductory Physics Calculus-Based

This equation sheet is intended for students writing tests or reviewing material. Therefore it is neither intended to be complete nor completely explicit. There are fewer symbols than variables, and so some symbols must be used for different things: context must distinguish.

The equations are mnemonic. Students are expected to understand how to interpret and use them.

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1 Constants

$$c = 2.99792458\times10^{8}\,\mathrm{m/s} \approx 2.998\times10^{8}\,\mathrm{m/s} \approx 3\times10^{8}\,\mathrm{m/s} \approx 1\,\mathrm{lyr/yr} \approx 1\,\mathrm{ft/ns} \qquad \text{exact by definition}$$

$$e = 1.602176487(40)\times10^{-19}\,\mathrm{C}$$

$$G = 6.67428(67)\times10^{-11}\,\mathrm{N\,m^2/kg^2} \qquad \text{(2006, CODATA)}$$

$$g = 9.8\,\mathrm{m/s^2} \qquad \text{fiducial value}$$

$$k = \frac{1}{4\pi\varepsilon_0} = 8.987551787\ldots\times10^{9} \approx 8.99\times10^{9} \approx 10^{10}\,\mathrm{N\,m^2/C^2}\text{exact by definition}$$

$$k_{\mathrm{Boltzmann}} = 1.3806504(24)\times10^{-23}\,\mathrm{J/K} = 0.8617343(15)\times10^{-4}\,\mathrm{eV/K} \approx 10^{-4}\,\mathrm{eV/K}$$

$$m_e = 9.10938215(45)\times10^{-31}\,\mathrm{kg} = 0.510998910(13)\,\mathrm{MeV}$$

$$m_p = 1.672621637(83)\times10^{-27}\,\mathrm{kg} = 938.272013(23), \mathrm{MeV}$$

$$\varepsilon_0 = \frac{1}{\mu_0 c^2} = 8.8541878176\ldots\times10^{-12}\,\mathrm{C^2/(N\,m^2)} \approx 10^{-11} \qquad \text{vacuum permittivity (exact by definition)}$$

$$\mu_0 = 4\pi\times10^{-7}\,\mathrm{N/A^2} \qquad \text{exact by definition}$$

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2 Geometrical Formulae

$$C_{\mathrm{cir}} = 2\pi r \qquad A_{\mathrm{cir}} = \pi r^2 \qquad A_{\mathrm{sph}} = 4\pi r^2 \qquad V_{\mathrm{sph}} = \frac{4}{3}\pi r^3$$

$$\Omega_{\mathrm{sphere}} = 4\pi \qquad d\Omega = \sin\theta\,d\theta\,d\phi$$

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3 Trigonometry Formulae

$$\frac{x}{r} = \cos\theta \qquad \frac{y}{r} = \sin\theta \qquad \frac{y}{x} = \tan\theta = \frac{\sin\theta}{\cos\theta} \qquad \cos^2\theta + \sin^2\theta = 1$$

$$\csc\theta = \frac{1}{\sin\theta} \qquad \sec\theta = \frac{1}{\cos\theta} \qquad \cot\theta = \frac{1}{\tan\theta}$$

$$c^2 = a^2 + b^2 \qquad c = \sqrt{a^2 + b^2 - 2ab\cos\theta_c} \qquad \frac{\sin\theta_a}{a} = \frac{\sin\theta_b}{b} = \frac{\sin\theta_c}{c}$$

$$f(\theta) = f(\theta + 360^\circ)$$

$$\sin(\theta + 180^\circ) = -\sin(\theta) \qquad \cos(\theta + 180^\circ) = -\cos(\theta) \qquad \tan(\theta + 180^\circ) = \tan(\theta)$$

$$\sin(-\theta) = -\sin(\theta) \qquad \cos(-\theta) = \cos(\theta) \qquad \tan(-\theta) = -\tan(\theta)$$

$$\sin(\theta+90^\circ)=\cos(\theta) \qquad \cos(\theta+90^\circ)=-\sin(\theta) \qquad \tan(\theta+90^\circ)=-\tan(\theta)$$

$$\sin(180^\circ-\theta)=\sin(\theta) \qquad \cos(180^\circ-\theta)=-\cos(\theta) \qquad \tan(180^\circ-\theta)=-\tan(\theta)$$

$$\sin(90^\circ-\theta)=\cos(\theta) \qquad \cos(90^\circ-\theta)=\sin(\theta) \qquad \tan(90^\circ-\theta)=\frac{1}{\tan(\theta)}=\cot(\theta)$$

$$\sin(a+b)=\sin(a)\cos(b)+\cos(a)\sin(b) \qquad \cos(a+b)=\cos(a)\cos(b)-\sin(a)\sin(b)$$

$$\sin(2a)=2\sin(a)\cos(a) \qquad \cos(2a)=\cos^2(a)-\sin^2(a)$$

$$\sin(a)\sin(b)=\frac{1}{2}\left[\cos(a-b)-\cos(a+b)\right] \qquad \cos(a)\cos(b)=\frac{1}{2}\left[\cos(a-b)+\cos(a+b)\right]$$

$$\sin(a)\cos(b)=\frac{1}{2}\left[\sin(a-b)+\sin(a+b)\right]$$

$$\sin^2\theta=\frac{1}{2}[1-\cos(2\theta)] \qquad \cos^2\theta=\frac{1}{2}[1+\cos(2\theta)] \qquad \sin(a)\cos(a)=\frac{1}{2}\sin(2a)$$

$$\cos(x)-\cos(y)=-2\sin\left(\frac{x+y}{2}\right)\sin\left(\frac{x-y}{2}\right)$$

$$\cos(x)+\cos(y)=2\cos\left(\frac{x+y}{2}\right)\cos\left(\frac{x-y}{2}\right)$$

$$\sin(x)+\sin(y)=2\sin\left(\frac{x+y}{2}\right)\cos\left(\frac{x-y}{2}\right)$$

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4 Approximation Formulae

$$\frac{\Delta f}{\Delta x}\approx\frac{df}{dx} \qquad \frac{1}{1-x}\approx 1+x\ :\ (x<<1)$$

$$\sin\theta\approx\theta \qquad \tan\theta\approx\theta \qquad \cos\theta\approx 1-\frac{1}{2}\theta^2 \qquad \text{all for } \theta<<1$$

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5 Quadratic Formula

If $\quad 0=ax^2+bx+c\ ,\quad$ then $\quad x=\dfrac{-b\pm\sqrt{b^2-4ac}}{2a}=-\dfrac{b}{2a}\pm\sqrt{\left(\dfrac{b}{2a}\right)^2-\dfrac{c}{a}}$

6 Vector Formulae

$$a = |\vec{a}| = \sqrt{a_x^2 + a_y^2} \qquad \theta = \tan^{-1}\left(\frac{a_y}{a_x}\right) + \pi? \qquad \vec{a} + \vec{b} = (a_x + b_x, a_y + b_y)$$

$$a = |\vec{a}| = \sqrt{a_x^2 + a_y^2 + a_z^2} \qquad \phi = \tan^{-1}\left(\frac{a_y}{a_x}\right) + \pi? \qquad \theta = \cos^{-1}\left(\frac{a_z}{a}\right)$$

$$\vec{a} + \vec{b} = (a_x + b_x, a_y + b_y, a_z + b_z)$$

$$\vec{a} \cdot \vec{b} = ab\cos\theta = a_x b_x + a_y b_y + a_z b_z$$

$$\vec{c} = \vec{a} \times \vec{b} = ab\sin(\theta)\hat{c} = (a_y b_z - b_y a_z, a_z b_x - b_z a_x, a_x b_y - b_x a_y)$$

7 Differentiation and Integration Formulae

$$\frac{d(x^p)}{dx} = px^{p-1} \quad \text{except for } p = 0; \qquad \frac{d(x^0)}{dx} = 0 \qquad \frac{d(\ln|x|)}{dx} = \frac{1}{x}$$

Taylor's series

$$\begin{aligned} f(x) &= \sum_{n=0}^{\infty} \frac{(x-x_0)^n}{n!} f^{(n)}(x_0) \\ &= f(x_0) + (x-x_0)f^{(1)}(x_0) + \frac{(x-x_0)^2}{2!} f^{(2)}(x_0) + \frac{(x-x_0)^3}{3!} f^{(3)}(x_0) + \ldots \end{aligned}$$

$$\int_a^b f(x)\,dx = F(x)|_a^b = F(b) - F(a) \quad \text{where} \quad \frac{dF(x)}{dx} = f(x)$$

$$\int x^n\,dx = \frac{x^{n+1}}{n+1} \quad \text{except for } n = -1; \qquad \int \frac{1}{x}\,dx = \ln|x|$$

8 One-Dimensional Kinematics

$$v_{\text{avg}} = \frac{\Delta x}{\Delta t} \qquad v = \frac{dx}{dt} \qquad a_{\text{avg}} = \frac{\Delta v}{\Delta t} \qquad a = \frac{dv}{dt} = \frac{d^2x}{dt^2}$$

$$v = at + v_0 \qquad x = \frac{1}{2}at^2 + v_0 t + x_0 \qquad v^2 = v_0^2 + 2a(x - x_0)$$

$$x = \frac{1}{2}(v_0 + v)t + x_0 \qquad x = -\frac{1}{2}at^2 + vt + x_0 \qquad g = 9.8\,\text{m/s}^2$$

$$x_{\mathrm{rel}} = x_2 - x_1 \qquad v_{\mathrm{rel}} = v_2 - v_1 \qquad a_{\mathrm{rel}} = a_2 - a_1$$

$$x' = x - v_{\mathrm{frame}} t \qquad v' = v - v_{\mathrm{frame}} \qquad a' = a$$

9 Two- and Three-Dimensional Kinematics: General

$$\vec{v}_{\mathrm{avg}} = \frac{\Delta \vec{r}}{\Delta t} \qquad \vec{v} = \frac{d\vec{r}}{dt} \qquad \vec{a}_{\mathrm{avg}} = \frac{\Delta \vec{v}}{\Delta t} \qquad \vec{a} = \frac{d\vec{v}}{dt} = \frac{d^2\vec{r}}{dt^2}$$

10 Projectile Motion

$$x = v_{x,0} t \qquad y = -\frac{1}{2} g t^2 + v_{y,0} t + y_0 \qquad v_{x,0} = v_0 \cos\theta \qquad v_{y,0} = v_0 \sin\theta$$

$$t = \frac{x}{v_{x,0}} = \frac{x}{v_0 \cos\theta} \qquad y = y_0 + x \tan\theta - \frac{x^2 g}{2 v_0^2 \cos^2\theta}$$

$$x_{\text{for } y \text{ max}} = \frac{v_0^2 \sin\theta \cos\theta}{g} \qquad y_{\max} = y_0 + \frac{v_0^2 \sin^2\theta}{2g}$$

$$x(y = y_0) = \frac{2 v_0^2 \sin\theta \cos\theta}{g} = \frac{v_0^2 \sin(2\theta)}{g} \qquad \theta_{\text{for max}} = \frac{\pi}{4} \qquad x_{\max}(y = y_0) = \frac{v_0^2}{g}$$

$$x(\theta = 0) = \pm v_0 \sqrt{\frac{2(y_0 - y)}{g}} \qquad t(\theta = 0) = \sqrt{\frac{2(y_0 - y)}{g}}$$

11 Relative Motion

$$\vec{r} = \vec{r}_2 - \vec{r}_1 \qquad \vec{v} = \vec{v}_2 - \vec{v}_1 \qquad \vec{a} = \vec{a}_2 - \vec{a}_1$$

12 Polar Coordinate Motion and Uniform Circular Motion

$$\omega = \frac{d\theta}{dt} \qquad \alpha = \frac{d\omega}{dt} = \frac{d^2\theta}{dt^2}$$

$$\vec{r} = r\hat{r} \qquad \vec{v} = \frac{d\vec{r}}{dt} = \frac{dr}{dt}\hat{r} + r\omega\hat{\theta} \qquad \vec{a} = \frac{d^2\vec{r}}{dt^2} = \left(\frac{d^2 r}{dt^2} - r\omega^2\right)\hat{r} + \left(r\alpha + 2\frac{dr}{dt}\omega\right)\hat{\theta}$$

$$\vec{v} = r\omega\hat{\theta} \qquad v = r\omega \qquad a_{\tan} = r\alpha$$

$$\vec{a}_{\mathrm{centripetal}} = -\frac{v^2}{r}\hat{r} = -r\omega^2\hat{r} \qquad a_{\mathrm{centripetal}} = \frac{v^2}{r} = r\omega^2 = v\omega$$

13 Very Basic Newtonian Physics

$$\vec{r}_{\text{cm}} = \frac{\sum_i m_i \vec{r}_i}{m_{\text{total}}} = \frac{\sum_{\text{sub}} m_{\text{sub}} \vec{r}_{\text{cm sub}}}{m_{\text{total}}} \qquad \vec{v}_{\text{cm}} = \frac{\sum_i m_i \vec{v}_i}{m_{\text{total}}} \qquad \vec{a}_{\text{cm}} = \frac{\sum_i m_i \vec{a}_i}{m_{\text{total}}}$$

$$\vec{r}_{\text{cm}} = \frac{\int_V \rho(\vec{r})\vec{r}\,dV}{m_{\text{total}}}$$

$$\vec{F}_{\text{net}} = m\vec{a} \qquad \vec{F}_{21} = -\vec{F}_{12} \qquad F_g = mg \qquad g = 9.8\,\text{m/s}^2$$

$$\vec{F}_{\text{normal}} = -\vec{F}_{\text{applied}} \qquad F_{\text{linear}} = -kx$$

$$f_{\text{normal}} = \frac{T}{r} \qquad T = T_0 - F_{\text{parallel}}(s) \qquad T = T_0$$

$$F_{\text{f static}} = \min(F_{\text{applied}}, F_{\text{f static max}}) \qquad F_{\text{f static max}} = \mu_{\text{static}} F_{\text{N}} \qquad F_{\text{f kinetic}} = \mu_{\text{kinetic}} F_{\text{N}}$$

$$v_{\text{tangential}} = r\omega = r\frac{d\theta}{dt} \qquad a_{\text{tangential}} = r\alpha = r\frac{d\omega}{dt} = r\frac{d^2\theta}{dt^2}$$

$$\vec{a}_{\text{centripetal}} = -\frac{v^2}{r}\hat{r} \qquad \vec{F}_{\text{centripetal}} = -m\frac{v^2}{r}\hat{r}$$

$$F_{\text{drag,lin}} = bv \qquad v_{\text{T}} = \frac{mg}{b} \qquad \tau = \frac{v_{\text{T}}}{g} = \frac{m}{b} \qquad v = v_{\text{T}}(1 - e^{-t/\tau})$$

$$F_{\text{drag,quad}} = bv^2 = \frac{1}{2}C\rho A v^2 \qquad v_{\text{T}} = \sqrt{\frac{mg}{b}}$$

14 Energy and Work

$$dW = \vec{F} \cdot d\vec{s} \qquad W = \int \vec{F} \cdot d\vec{s} \qquad KE = \frac{1}{2}mv^2 \qquad E_{\text{mechanical}} = KE + PE$$

$$P_{\text{avg}} = \frac{\Delta W}{\Delta t} \qquad P = \frac{dW}{dt} \qquad P = \vec{F} \cdot \vec{v}$$

$$\Delta KE = W_{\text{net}} \quad \Delta PE_{\text{of a conservative force}} = -W_{\text{by a conservative force}} \quad \Delta E = W_{\text{nonconservative}}$$

$$F = -\frac{dPE}{dx} \qquad \vec{F} = -\nabla PE \qquad PE = \frac{1}{2}kx^2 \qquad PE = mgy$$

15 Momentum

$$\vec{F}_{\text{net}} = m\vec{a}_{\text{cm}} \qquad \Delta KE_{\text{cm}} = W_{\text{net,external}} \qquad \Delta E_{\text{cm}} = W_{\text{not}}$$

$$\vec{p} = m\vec{v} \qquad \vec{F}_{\text{net}} = \frac{d\vec{p}}{dt} \qquad \vec{F}_{\text{net}} = \frac{d\vec{p}_{\text{total}}}{dt}$$

$$m\vec{a}_{\text{cm}} = \vec{F}_{\text{net non-flux}} + (\vec{v}_{\text{flux}} - \vec{v}_{\text{cm}})\frac{dm}{dt} = \vec{F}_{\text{net non-flux}} + \vec{v}_{\text{rel}}\frac{dm}{dt}$$

$$v = v_0 + v_{\text{ex}} \ln\left(\frac{m_0}{m}\right) \qquad \text{rocket in free space}$$

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16 Collisions

$$\vec{I} = \int_{\Delta t} \vec{F}(t)\,dt \qquad \vec{F}_{\text{avg}} = \frac{\vec{I}}{\Delta t} \qquad \Delta p = \vec{I}_{\text{net}}$$

$$\vec{p}_{1i} + \vec{p}_{2i} = \vec{p}_{1f} + \vec{p}_{2f} \qquad \vec{v}_{\text{cm}} = \frac{\vec{p}_1 + \vec{p}_2}{m_{\text{total}}}$$

$$KE_{\text{total }f} = KE_{\text{total }i} \qquad \text{1-d Elastic Collision Expression}$$

$$v_{1'} = \frac{(m_1 - m_2)v_1 + 2m_2v_2}{m_1 + m_2} \qquad \text{1-d Elastic Collision Expression}$$

$$v_{2'} - v_{1'} = -(v_2 - v_1) \qquad v_{\text{rel}'} = -v_{\text{rel}} \qquad \text{1-d Elastic Collision Expressions}$$

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17 Rotational Kinematics

$$2\pi = 6.2831853\ldots \qquad \frac{1}{2\pi} = 0.15915494\ldots$$

$$\frac{180^\circ}{\pi} = 57.295779\ldots \approx 60^\circ \qquad \frac{\pi}{180^\circ} = 0.017453292\ldots \approx \frac{1}{60^\circ}$$

$$\theta = \frac{s}{r} \qquad \omega = \frac{d\theta}{dt} = \frac{v}{r} \qquad \alpha = \frac{d^2\theta}{dt^2} = \frac{d\omega}{dt} = \frac{a}{r} \qquad f = \frac{\omega}{2\pi} \qquad P = \frac{1}{f} = \frac{2\pi}{\omega}$$

$$\omega = \alpha t + \omega_0 \qquad \Delta\theta = \frac{1}{2}\alpha t^2 + \omega_0 t \qquad \omega^2 = \omega_0^2 + 2\alpha\Delta\theta$$

$$\Delta\theta = \frac{1}{2}(\omega_0 + \omega)t \qquad \Delta\theta = -\frac{1}{2}\alpha t^2 + \omega t$$