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Tools for Peer Instruction — A Workshop



Pre-conference Workshop
1st International Conference on Teaching and Learning
Muscat, Oman, 9 February 2020



Tools for Peer Instruction — A Workshop



@eric_mazur

Pre-conference Workshop
1st International Conference on Teaching and Learning
Muscat, Oman, 9 February 2020









1 education

2 PI

3 PI 2.0

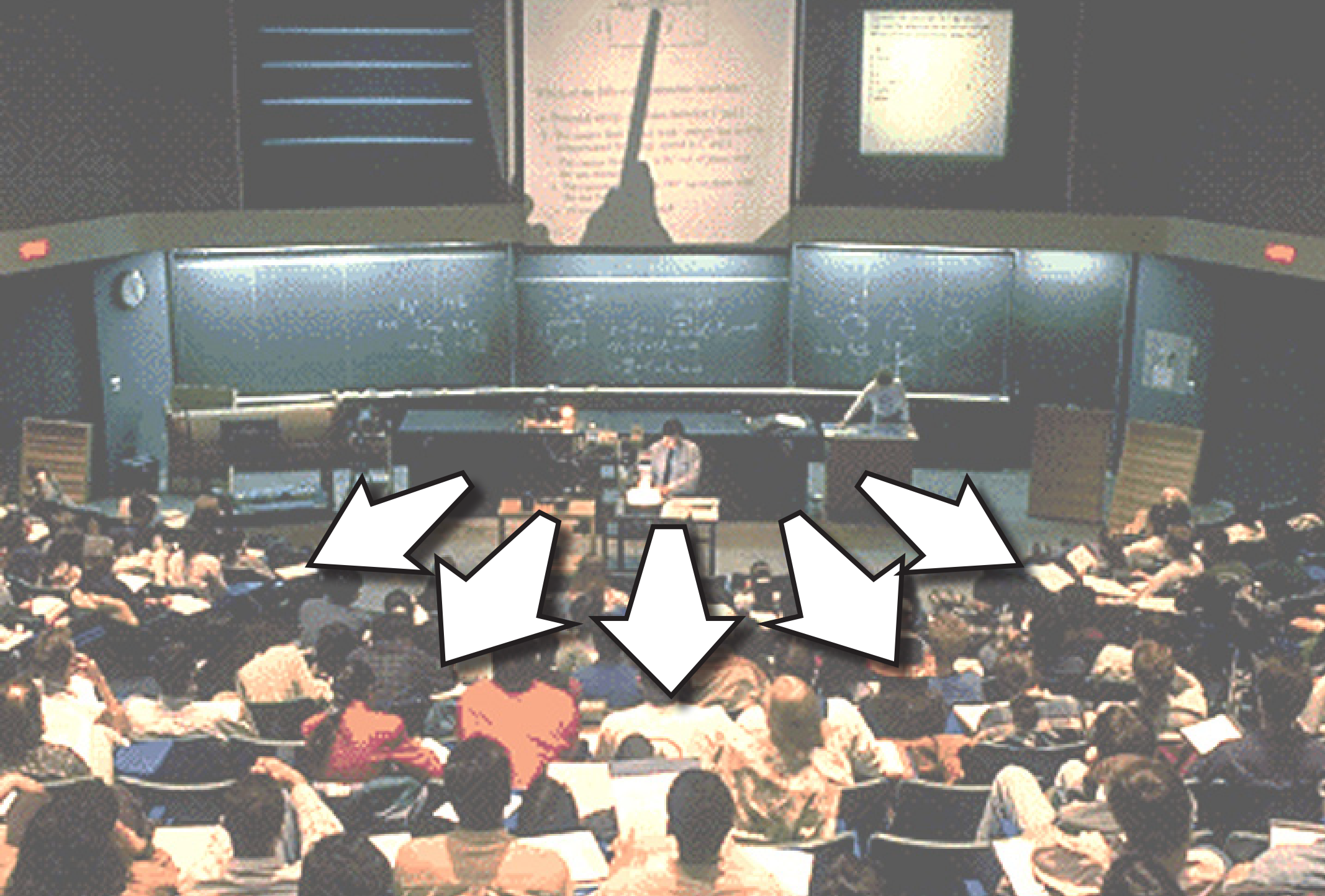


1 education

2 PI

3 PI 2.0







1. transfer of information



1. transfer of information

2. assimilation of that information



1. transfer of information (in class)

2. assimilation of that information



1. transfer of information (in class)

2. assimilation of that information (out of class)



**Should focus
on THIS!**

1. transfer of information (in class)

2. assimilation of that information (out of class)

- 
1. transfer of information (in class)
 2. assimilation of that information (out of class)

- 
1. transfer of information (out of class)
 2. assimilation of that information (in class)



Peer

1. transfer of information (out of class)

2. assimilation of that information (in class)



feedback

1 lecture

2 PI

3 PI 2.0



1991

① lecture

② PI

③ PI 2.0



1993



1998





1 lecture

2 PI

3 PI 2.0



How do I...

- design good questions?
- optimize the discussions?
- manage time?

Use intelligent algorithms and data analytics to...

- **improve questioning**
 - **manage discussions**
 - **facilitate time management/flow**
- learning | catalytics

- lowest
- a. A 30-year fixed rate mortgage at 12%
 - b. A 15-year fixed rate mortgage at 12%
 - c. A 30-year fixed rate mortgage at 12%
 - d. A 15-year fixed rate mortgage at 12%
2. The biggest factor that leads American companies to manufacture their products overseas in India is:
- a. Higher quality of craftsmanship
 - b. Lower labor costs
 - c. Decreased transportation costs
 - d. Effective legal systems
3. Which of the following correctly summarizes the accounting equation for a sole proprietorship?
- a. $\text{Assets} = \text{Liabilities} + \text{Owners' equity}$
 - b. $\text{Liabilities} = \text{Assets} + \text{Owners' equity}$
 - c. $\text{Owner's equity} = \text{Assets} + \text{Liabilities}$
 - d. $\text{Revenue} = \text{Assets} - \text{Liabilities}$
4. In order to present a business plan to a group of potential investors, a businessperson would most likely use which of the following?
- a. Powerpoint
 - b. Quickbooks
 - c. Peoplesoft
 - d. Excel
5. In order to start an online business, and individual would need all but which of the following:
- a. business model
 - b. depreciation?

extensible plug-in architecture for question types

Sample question types:

- direction
- mathematical expression
- long answer, short answer, word cloud
- numerical, data collection
- ranking, priority
- region (select point on image)
- sketch, composite sketch
- highlight passage

Sample question types:

- direction
- mathematical expression
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- highlight passage



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4. direction
prevailing

...le. The image provides several clues about the direction of
...on your screen.

 [Deliver](#)

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1 lecture

3 PI 2.0

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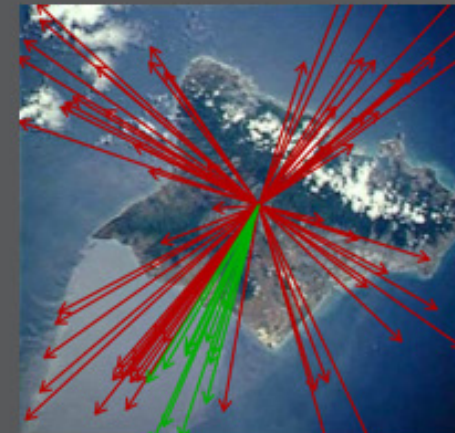
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4. direction
prevailing

...tle. The image provides several clues about the direction of
...on your screen.

[Deliver](#) [Show all results](#)**Round 1**

77 responses, 16% correct



✓ 17 get it now

✗ 3 still don't get it

1 lecture**3** PI 2.0

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optics i

current session: **766079** | 69 students[Back to all lectures](#) [Stop session](#) [Review results](#) [Seat map](#) [Show floating session ID](#) [Edit](#) [Delete](#)

Jump to ▼

1

2

3

4

5

6

7

8

9

10

11

12

13

14

15

**4.** direction Light enters horizontally into the combination of two perpendicular mirrors as shown below.[Deliver](#) [Show all results](#)

Indicate the direction of the incident light after it reflects off of both mirrors.



feedback & support

1 lecture**2** PI**3** PI 2.0

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optics i

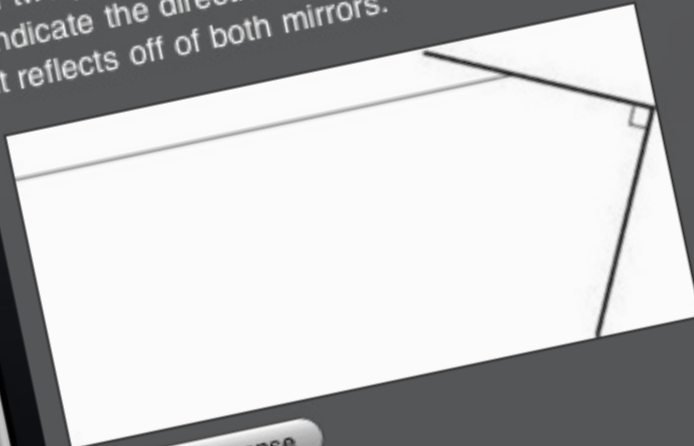
current session: **766079** | 69 students[Map](#) [Show floating session ID](#) [Edit](#) [Delete](#)

6 7 8 9 10 11 12 13 14 15

perpendicular mirrors as shown below.

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Light enters horizontally into the combination of two perpendicular mirrors as shown below. Indicate the direction of the incident light after it reflects off of both mirrors.

[Submit response](#)[Switch to text response](#)[feedback & support](#)**1** lecture**3** PI 2.0

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6 7 8 9 10 11 12 13 14 15

pendicular mirrors as shown below.

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Indicate the d

1 lecture**3** PI 2.0

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6 7 8 9 10 11 12 13 14 15



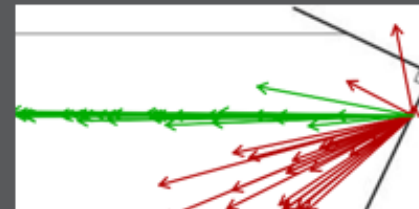
perpendicular mirrors as shown below.

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Round 1



57 responses, 58% correct



feedback & support

1 lecture

3 PI 2.0

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optics i

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6 7 8 9 10 11 12 13 14 15



perpendicular mirrors as shown below.

[Deliver](#) [Show all results](#)

Round 1

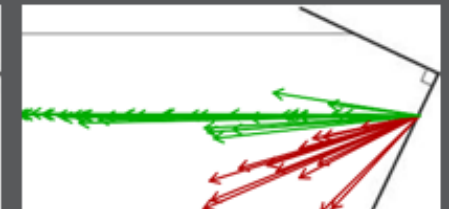
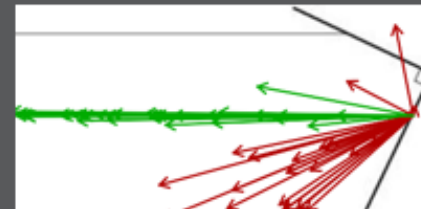


57 responses, 58% correct

Round 2



51 responses, 73% correct



✓ 8 get it now

✗ 0 still don't get it



feedback & support

1 lecture

3 PI 2.0

Sample question types:

- direction
- mathematical expression
- long answer, short answer, word cloud
- numerical, data collection
- ranking, priority
- region (select point on image)
- sketch, composite sketch
- highlight passage

If $2x - y = 4$, then $x =$

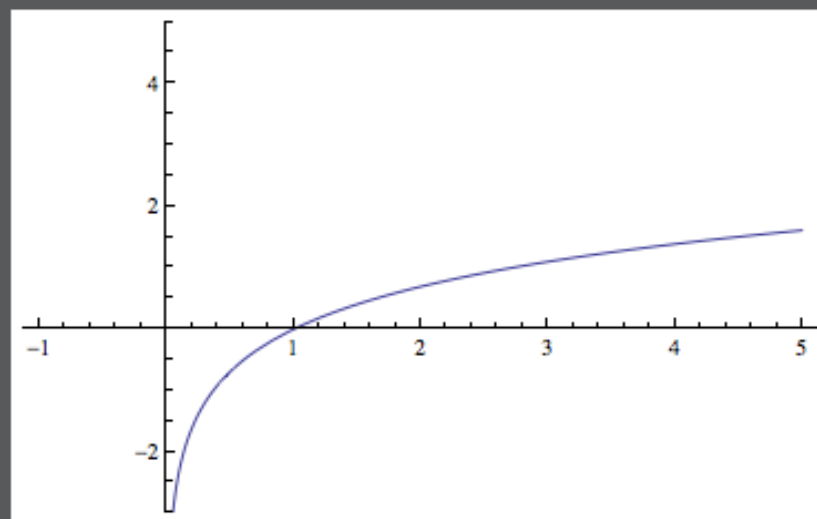
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- sketch, composite sketch
- highlight passage

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This is a graph of $f(x) = \ln x$. Sketch a graph of the derivative $f'(x)$.

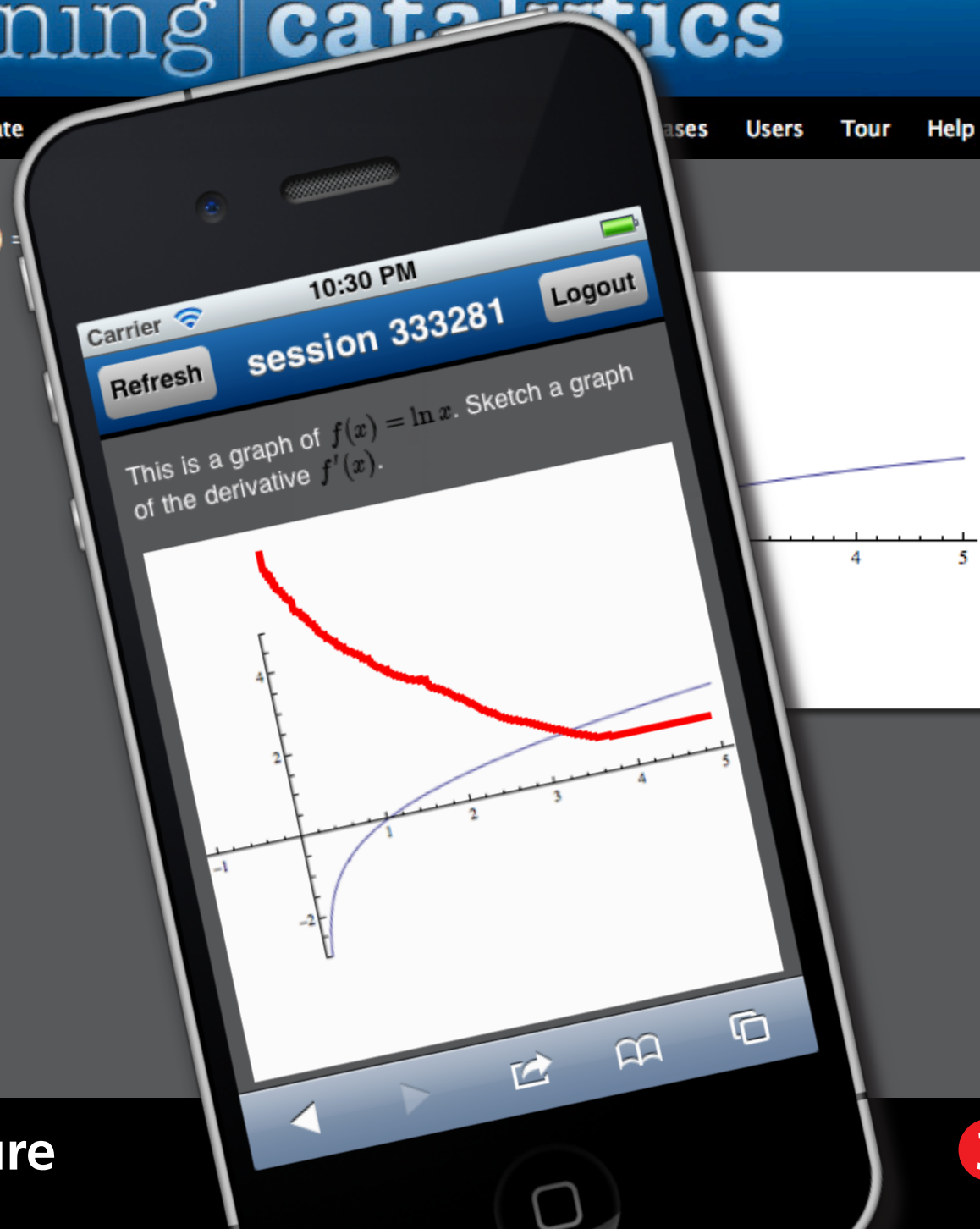


1 lecture

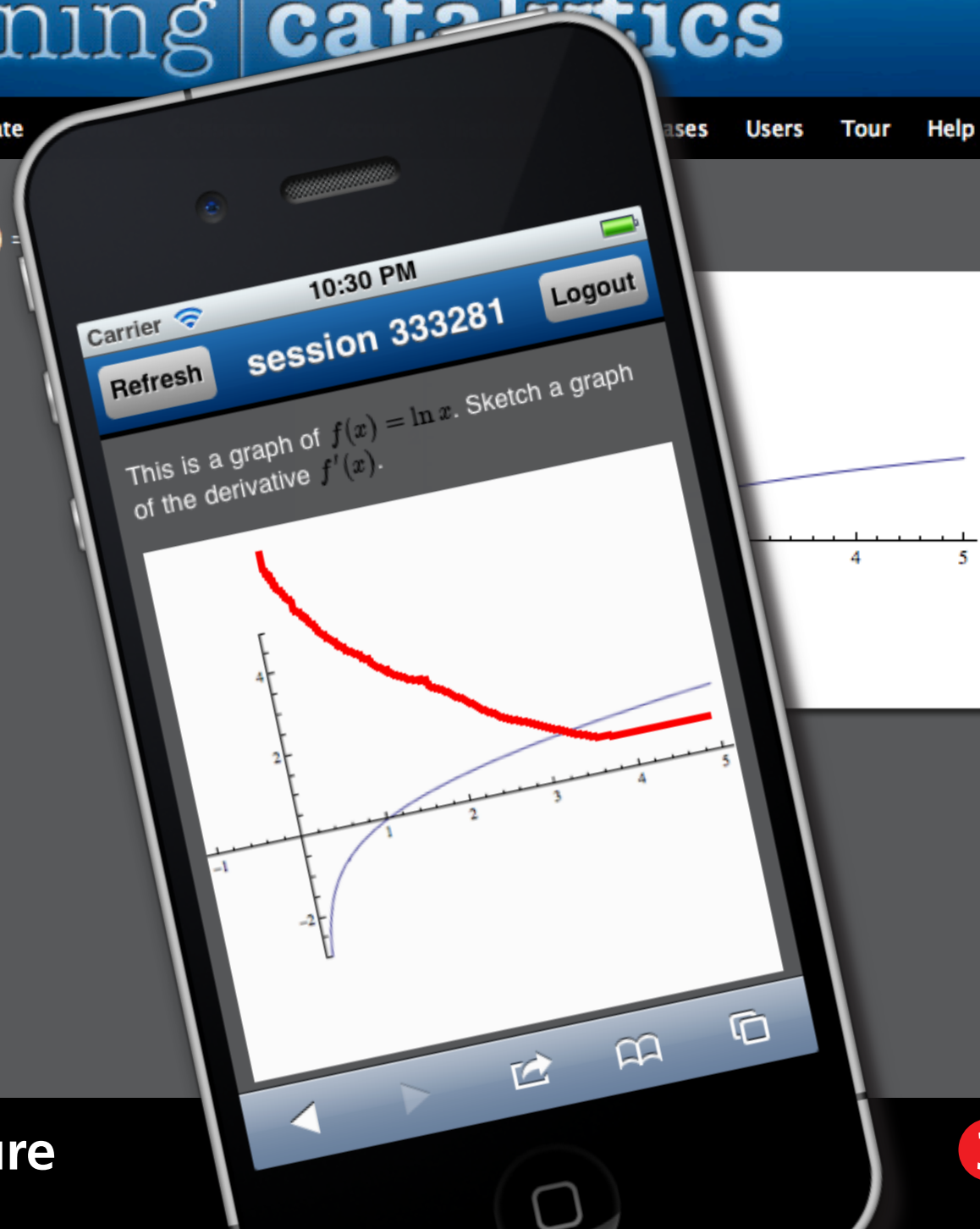
2 PI

3 PI 2.0

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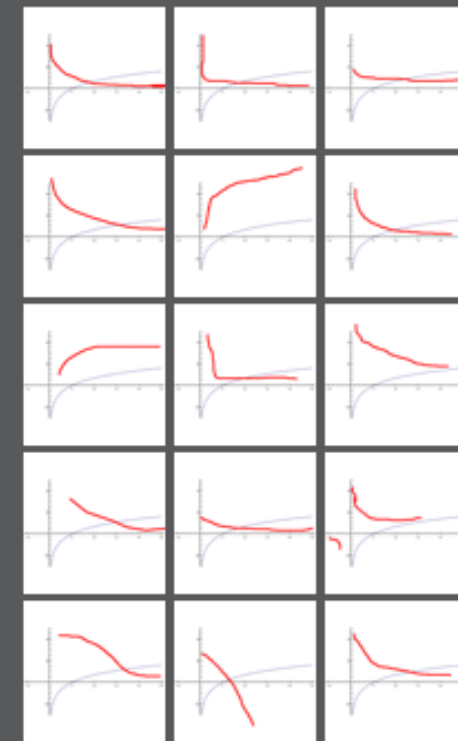
[Courses](#) [Participate](#)[ases](#) [Users](#) [Tour](#) [Help](#)This is a graph of $f(x) =$ **1** lecture**3** PI 2.0

learning | catalytics

[Courses](#) [Participate](#)[ases](#) [Users](#) [Tour](#) [Help](#)This is a graph of $f(x) =$ 

Round 1

15 responses



✓ 6 get it now
✗ 0 still don't get it

1 lecture

3 PI 2.0

Sample question types:

- direction
- mathematical expression
- long answer, short answer, word cloud
- numerical data collection
- ranking priority
- region (select point on image)
- sketch, composite sketch
- highlight passage



1 lecture

2 PI

3 PI 2.0



human interaction

1 lecture

2 PI

3 PI 2.0

Carrier 9:31 PM 100%

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review results for session 399757 in electrostatic work and energy ii

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Jump to 1 2 3 4 5 6 7 8 9 10 11 12 13 14 15 16 17 18 19

A positively charged rod is held near a neutral conducting sphere as illustrated below. A positively charged particle is moved from point A to point B



Round 1
74 responses, 61% correct

A. 61%
B. 4%
C. 35%
D. 0%
E. 0%

Round 2
75 responses, 83% correct

A. 83%
B. 0%
C. 17%
D. 0%
E. 0%

A. positive
B. zero
C. negative
D. depends on the path taken from A to B
E. cannot be determined without knowing more about the polarization induced in the sphere

Search:

1 lecture

2 PI

3 PI 2.0

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A positively charged rod is held near a neutral conducting sphere as illustrated below. A positively charged particle is moved from point A to point B at constant speed. The potential difference from A to B is

A. positive
B. zero
C. negative
D. depends on the path taken from A to B
E. cannot be determined without knowing more about the polarization induced in the sphere

Round 1
74 responses, 61% correct

A. 61%
B. 4%
C. 35%
D. 0%
E. 0%

Round 2
75 responses, 83% correct

A. 83%
B. 0%
C. 17%
D. 0%
E. 0%

Search: _____

Carrier 9:31 PM 100%

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Jump to 1 2 3 4 5 6 7 8 9 10 11 12 13 14 15 16 17 18 19

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A. 61%
B. 4%
C. 35%
D. 0%
E. 0%

Round 2 75 responses, 83% correct

A. 83%
B. 0%
C. 17%
D. 0%
E. 0%

A. positive
B. zero
C. negative
D. depends on the path taken from A to B
E. cannot be determined without knowing more about the polarization induced in the sphere

Search:

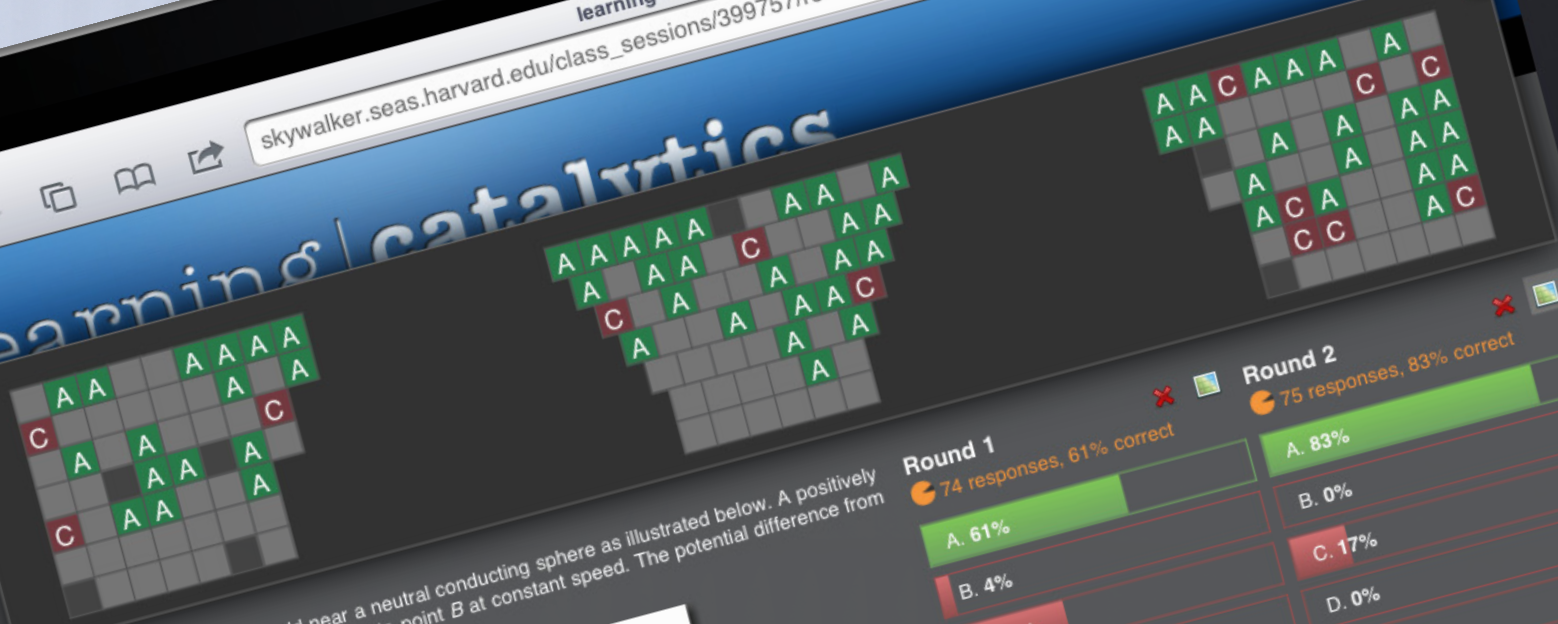
1 lecture

2 PI

3 PI 2.0

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A positively charged rod is held near a neutral conducting sphere as illustrated below. A positively charged particle is moved from point A to point B at constant speed. The potential difference from A to B is



A. positive
 B. zero
 C. negative
 D. depends on the path taken from A to B
 E. cannot be determined without knowing more about the polarization induced in the sphere

Round 1
 74 responses, 61% correct

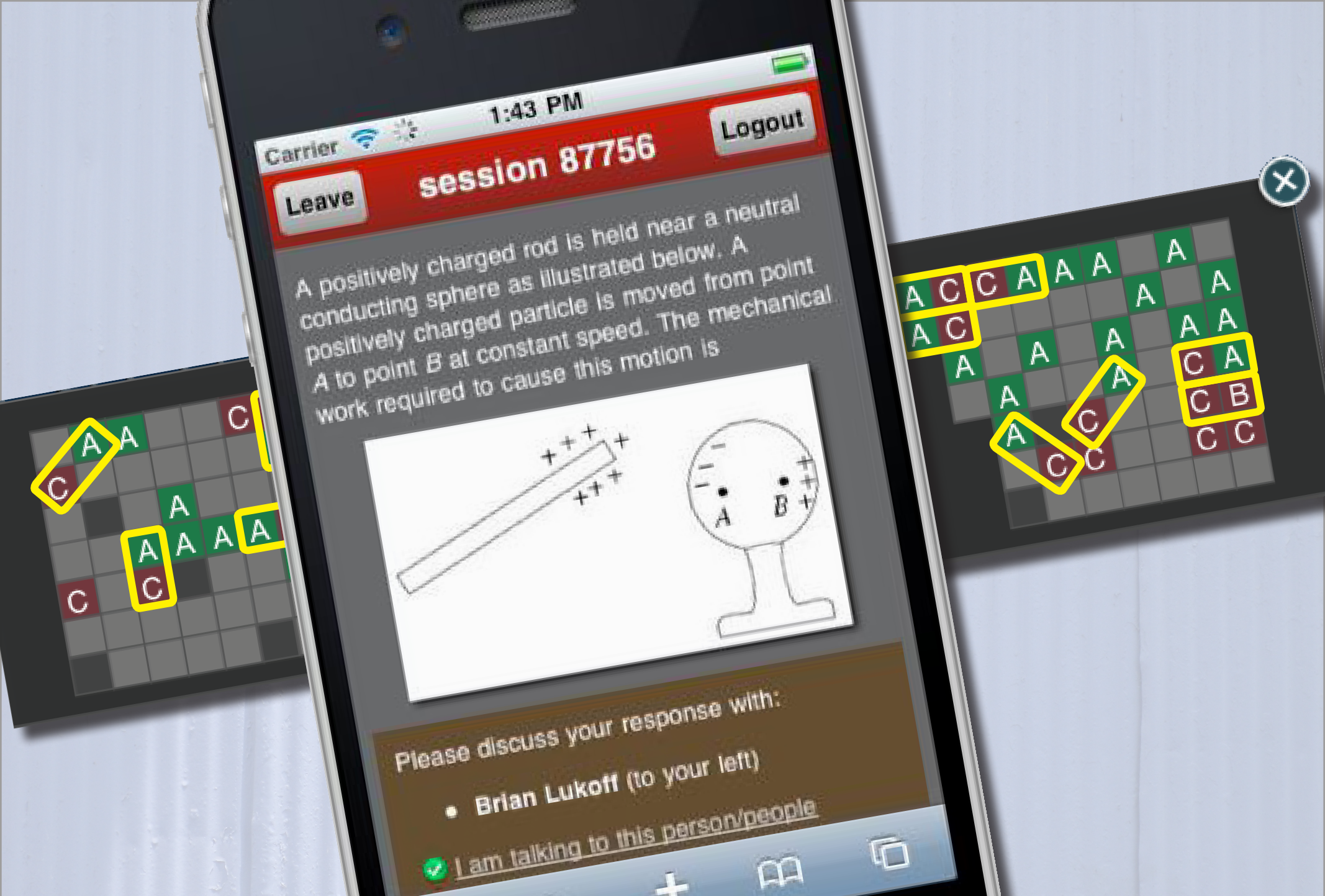
A. 61%
B. 4%
C. 35%
D. 0%
E. 0%

Round 2
 75 responses, 83% correct

A. 83%
B. 0%
C. 17%
D. 0%
E. 0%

Search:

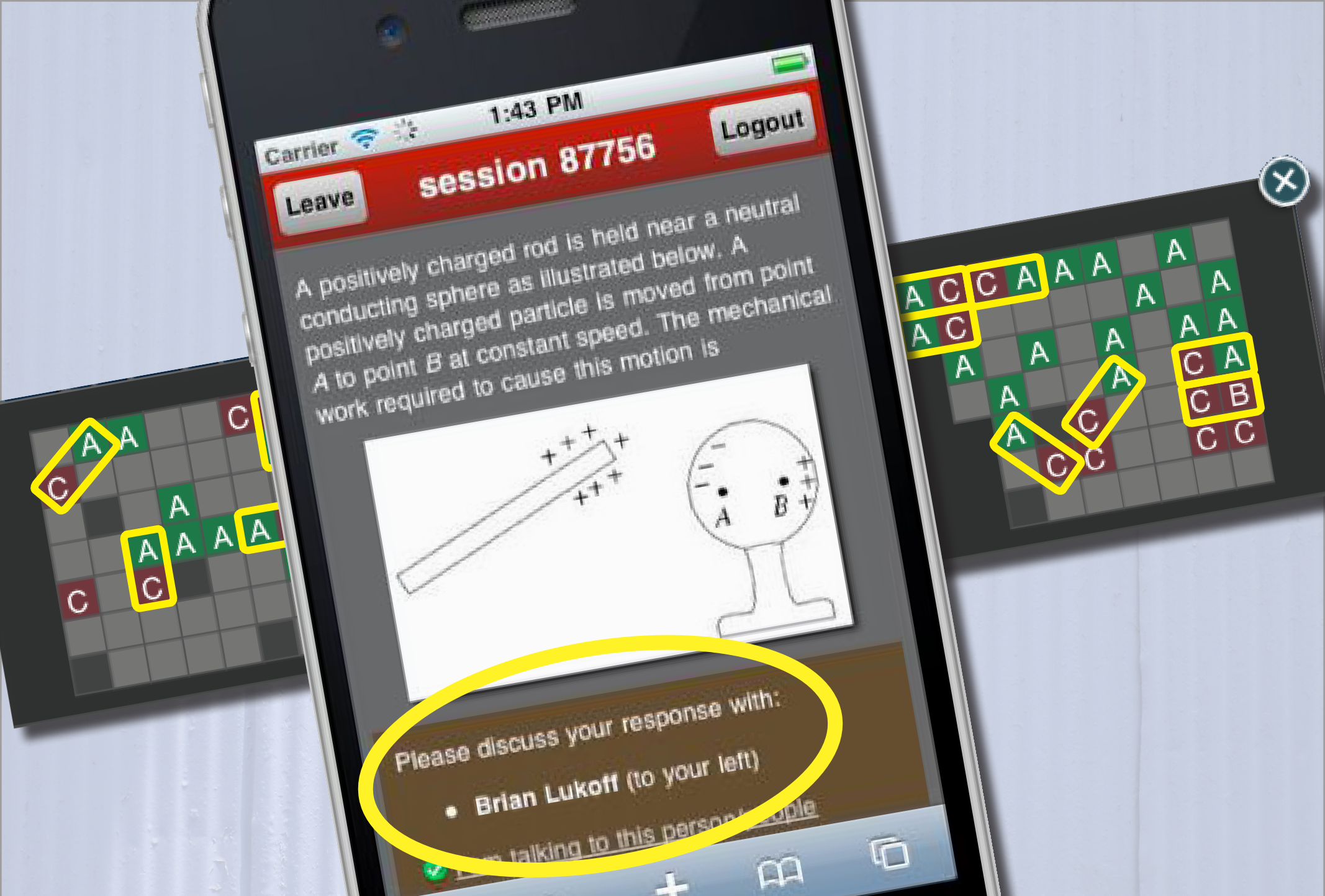
let system manage pairing



1 lecture

2 PI

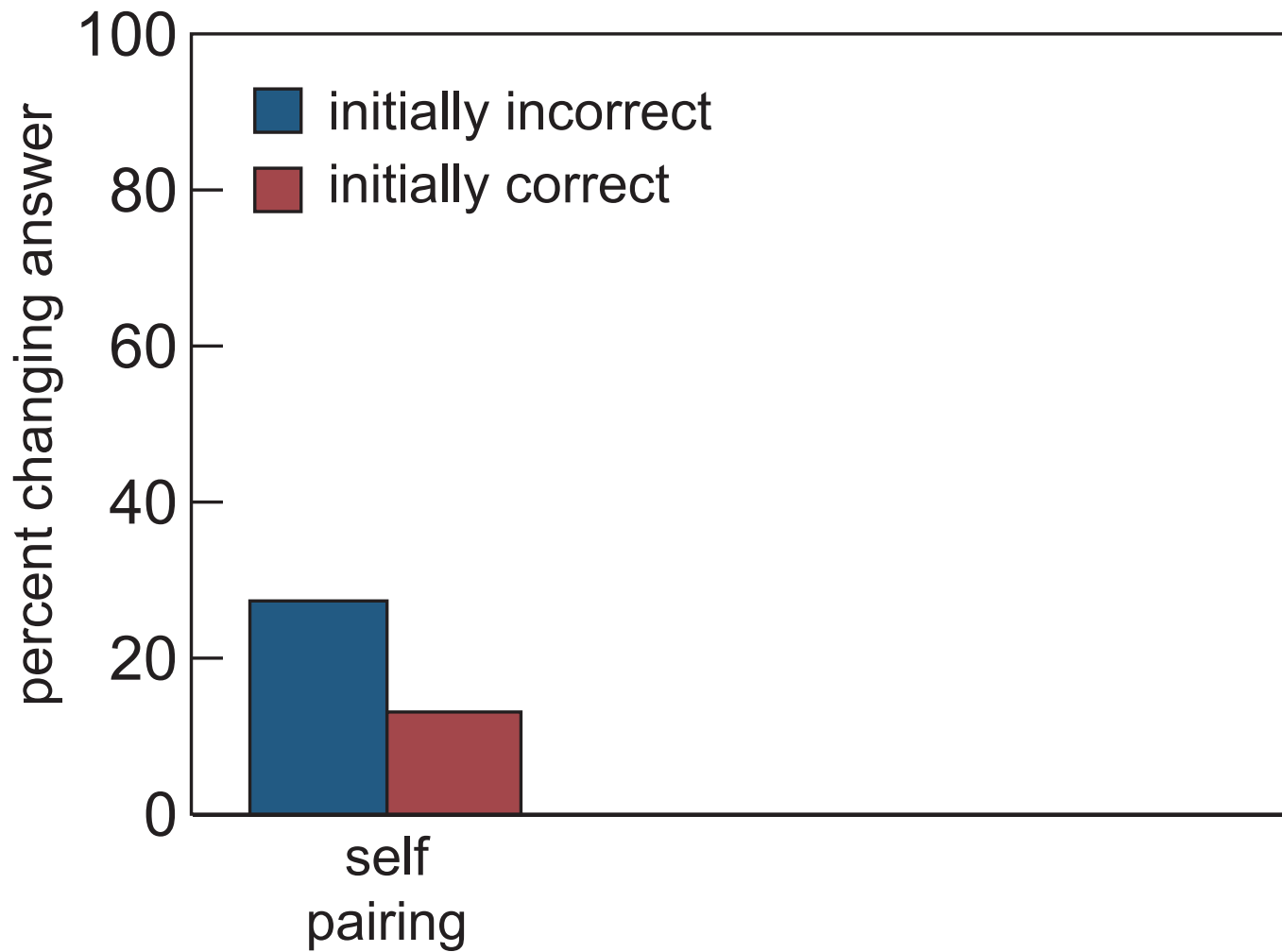
3 PI 2.0

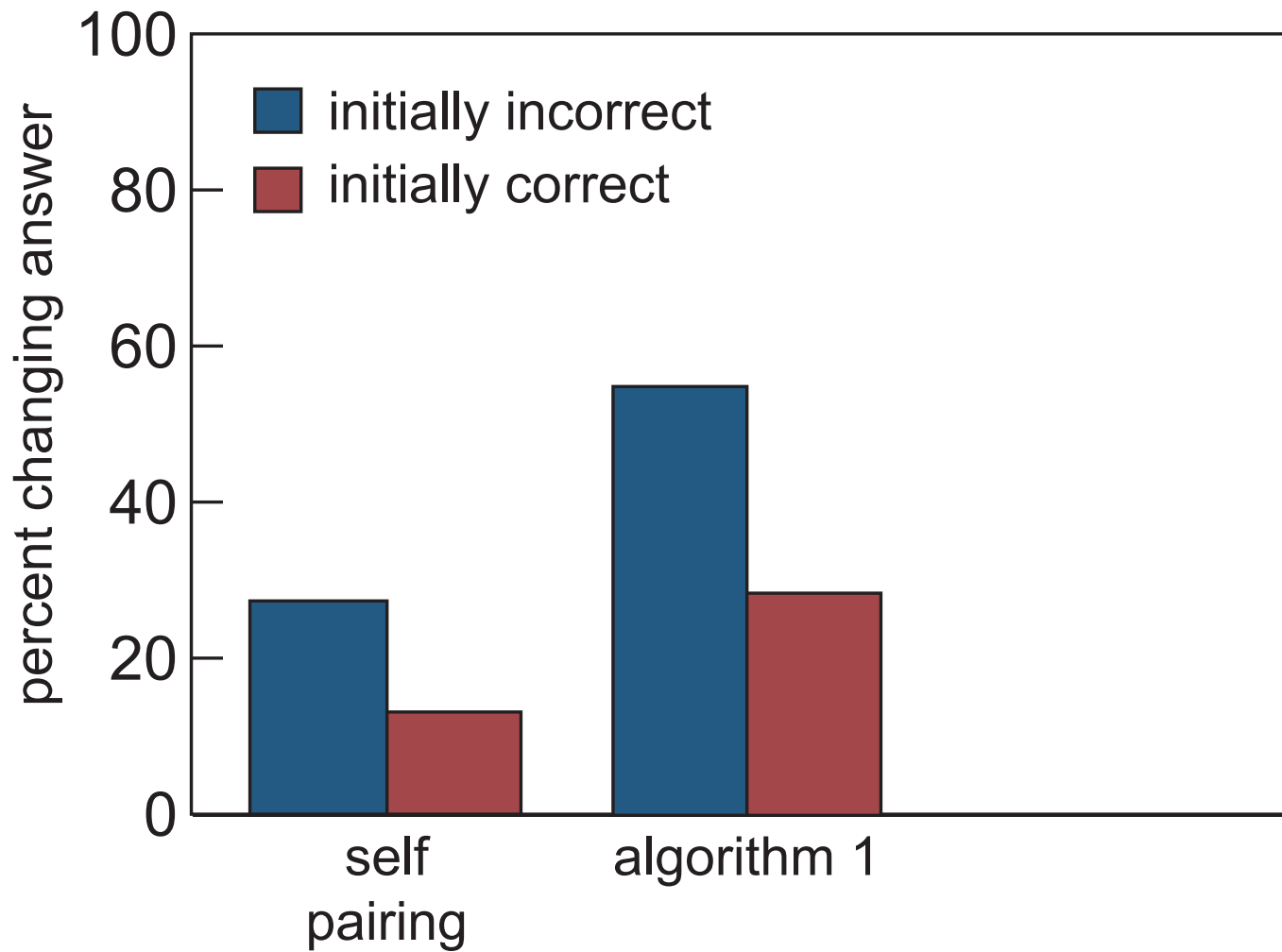


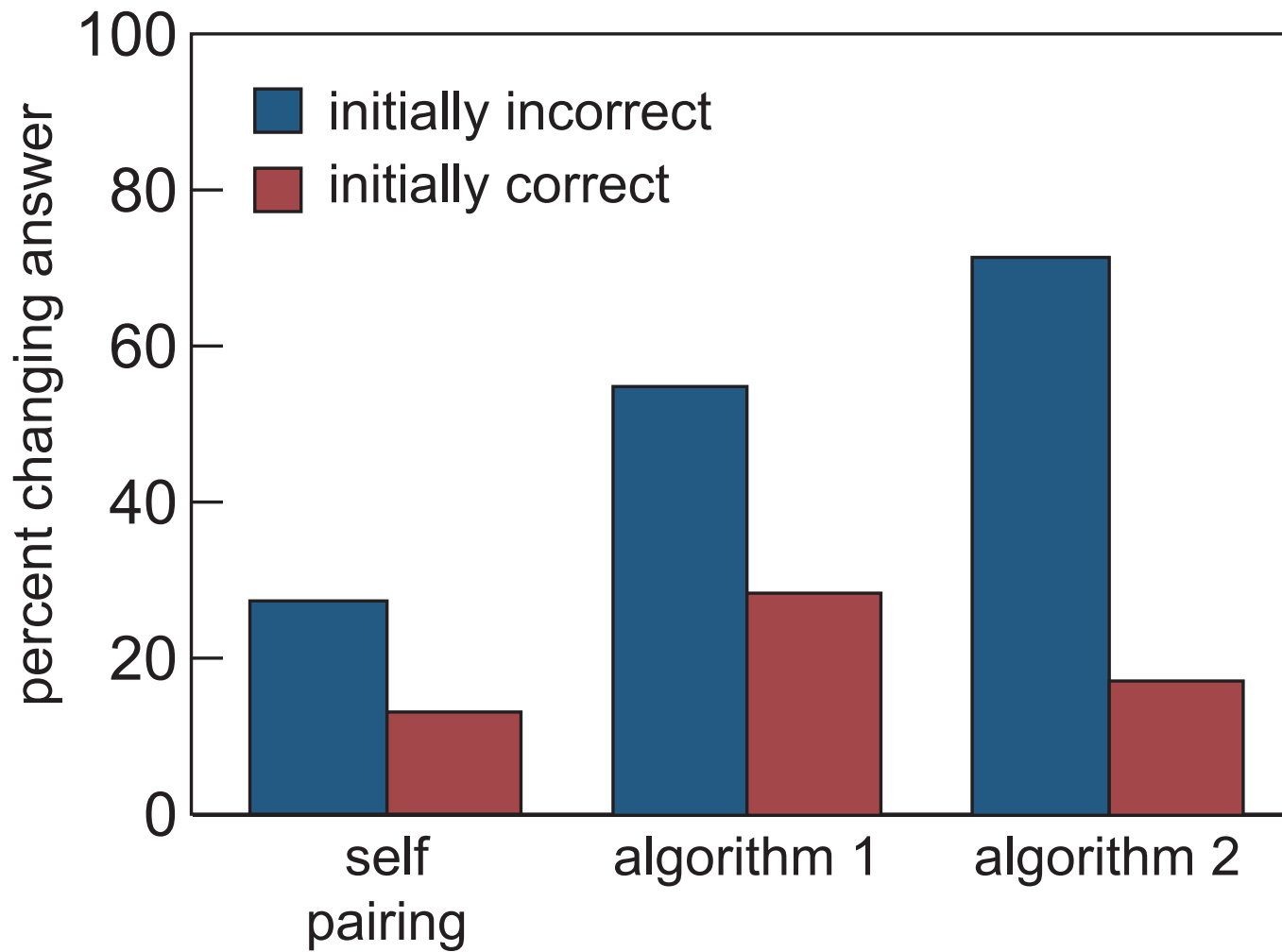
1 lecture

2 PI

3 PI 2.0





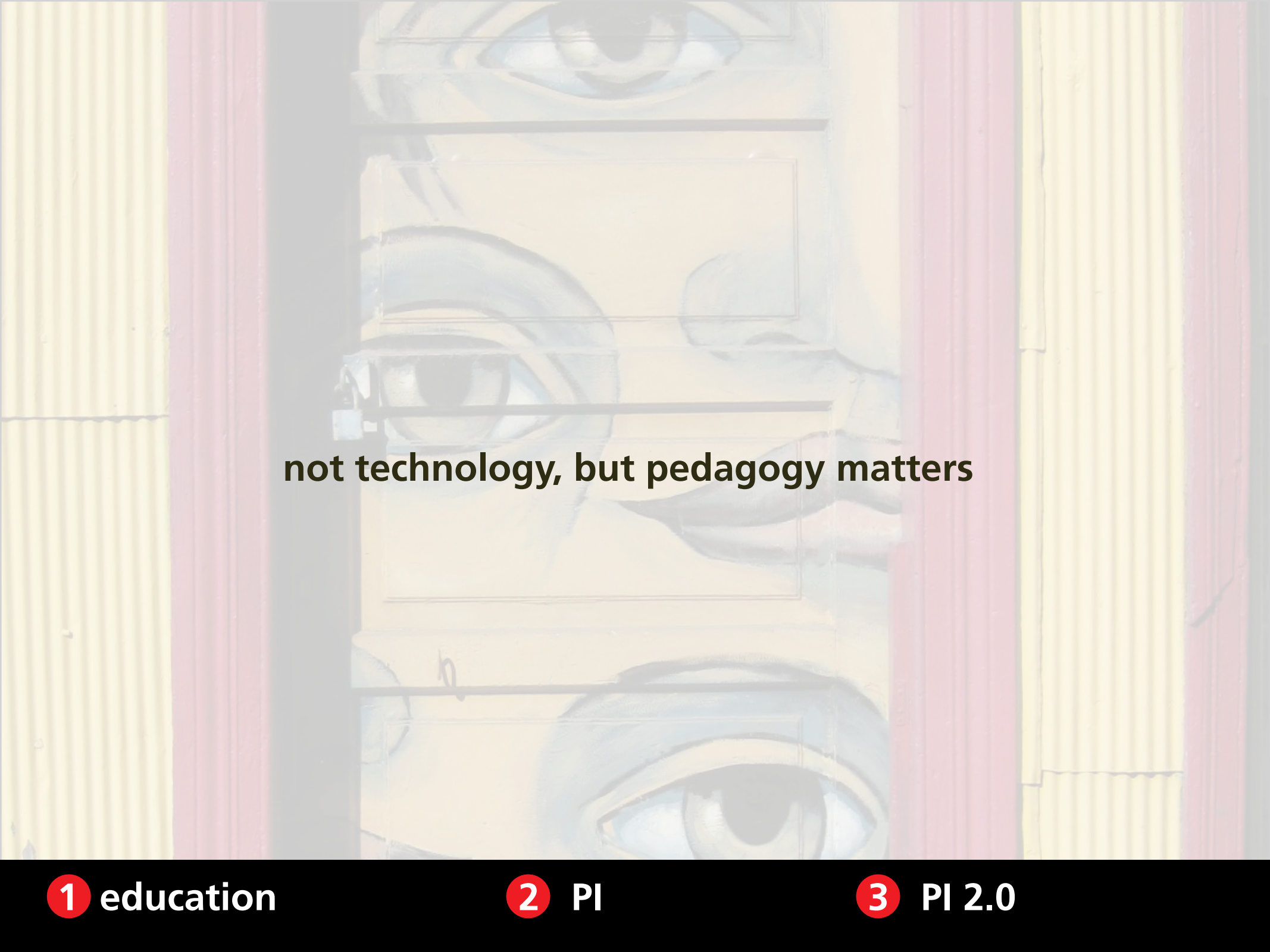




1 lecture

2 PI

3 PI 2.0



not technology, but pedagogy matters

1 education

2 PI

3 PI 2.0

IMMEDIATE FEEDBACK ASSESSMENT TECHNIQUE (IF AT)













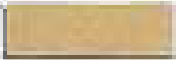






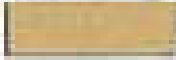





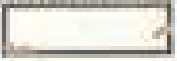

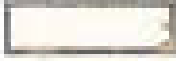
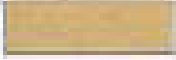

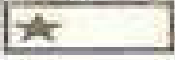





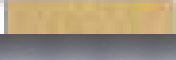
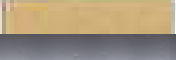
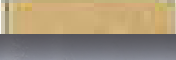
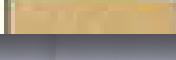
Name Team #3

Test # 1

Subject _____

Total 23

SCRATCH OFF COVERING TO EXPOSE ANSWER

	A	B	C	D	Score
1.					<u>4</u>
2.					<u>2</u>
3.					<u>4</u>
4.					<u>1</u>
5.					<u>4</u>
6.					<u>4</u>
7.					<u>0</u>
8.					<u>4</u>
9.					_____
10.					_____



not technology, but pedagogy matters

1 education

2 PI

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ROOM

deeper understanding



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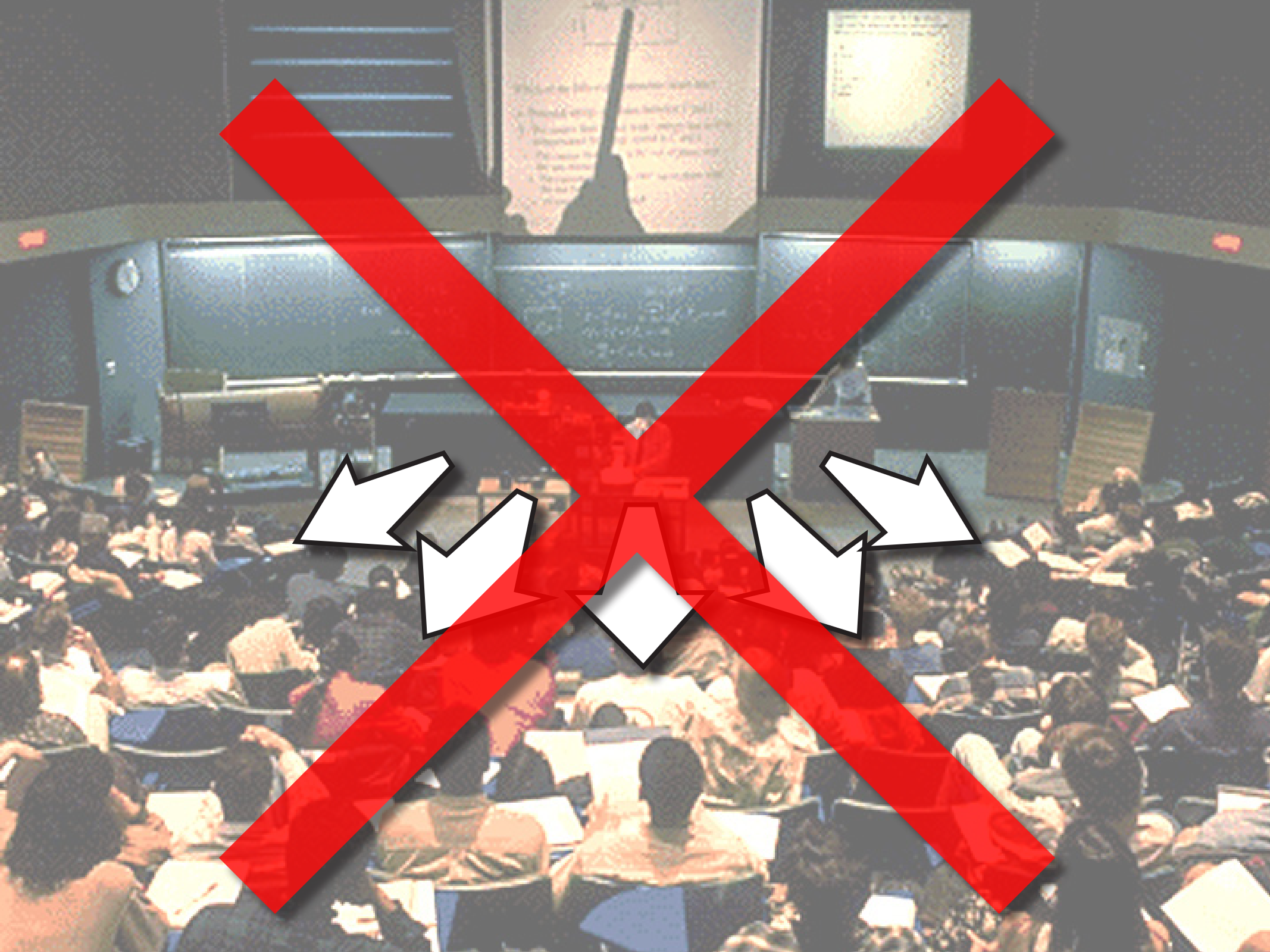
deeper understanding



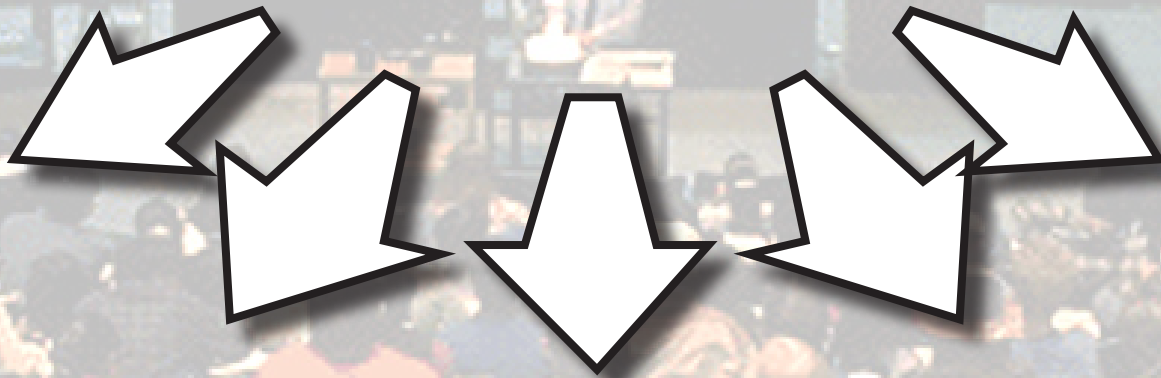
1st exposure



deeper understanding



how to effectively transfer information outside classroom?





but...



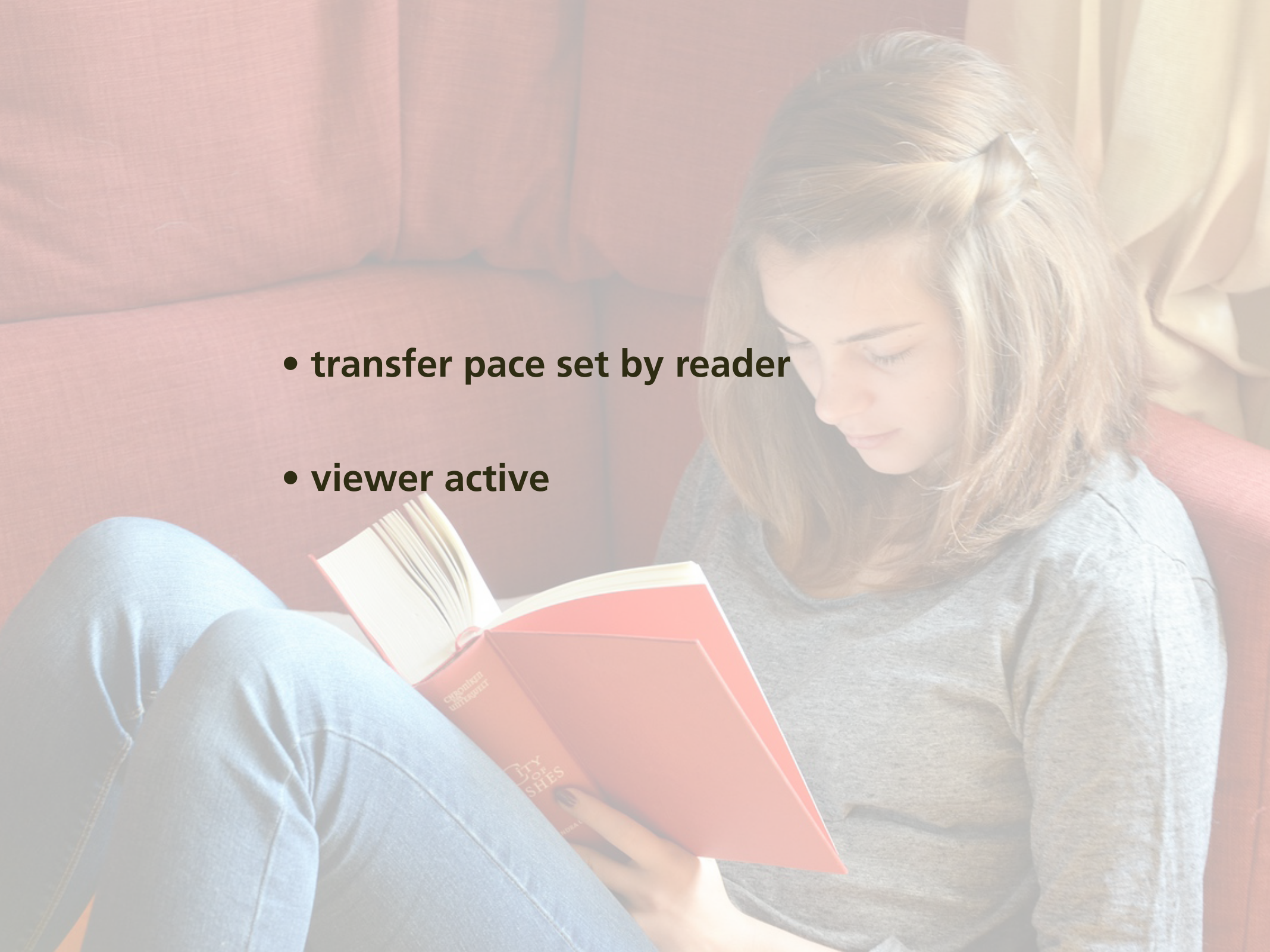
- transfer pace set by video
- viewer passive
- viewing/attention tanks as time passes
- isolated/individual experience






we're simply moving this outside classroom!



- 
- **transfer pace set by reader**
 - **viewer active**

but...





**isolated/individual experience &
no real accountability**



want:
every student prepared for every class



want:
every student prepared for every class
(without additional instructor effort)

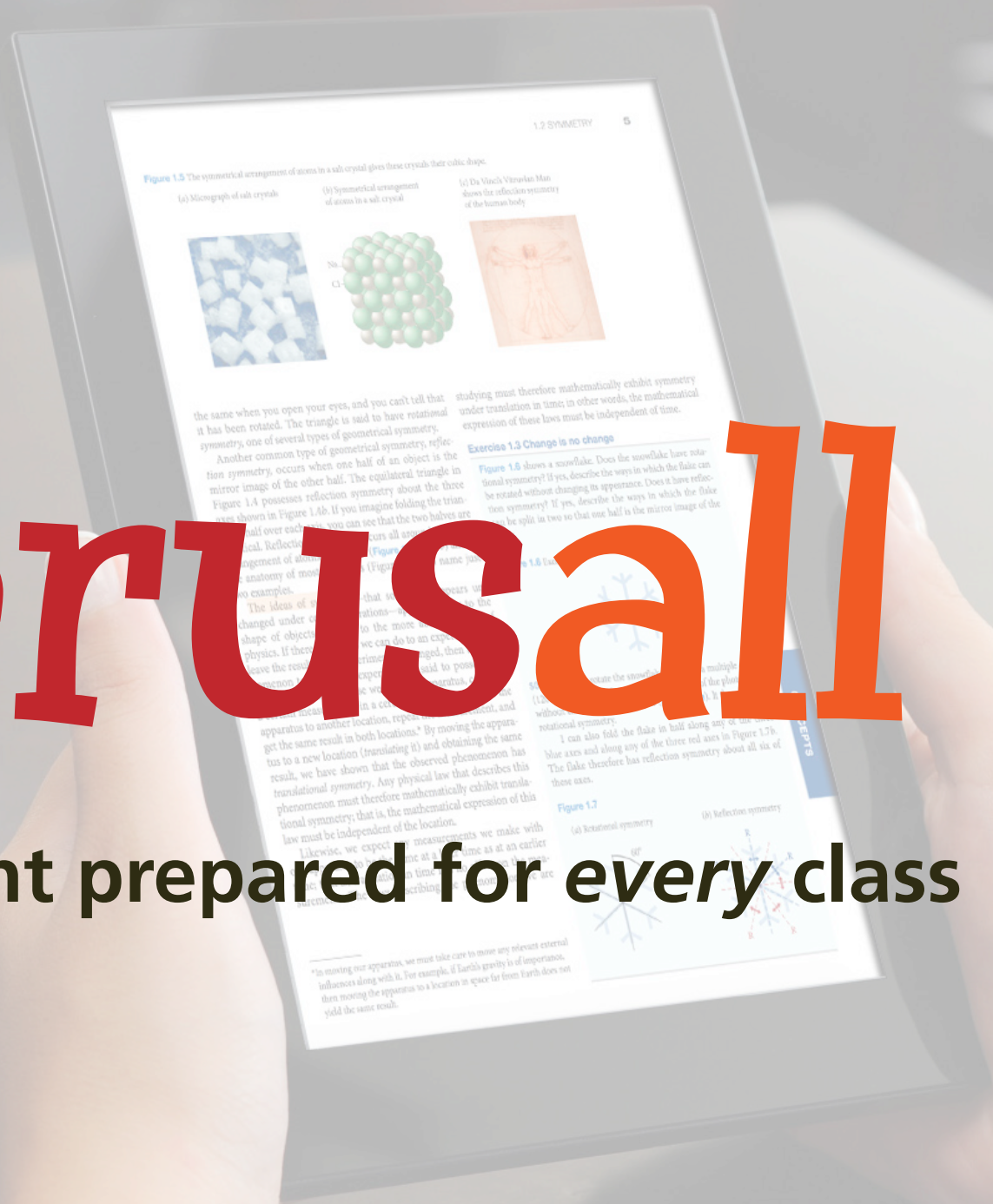
A stylized illustration of a classroom with several students sitting at desks. The students are represented by simplified, colorful shapes in shades of yellow, green, blue, purple, and pink. They are all facing forward, and some are holding pens or pencils. The desks are light brown, and the background is a solid light gray.

Solution

**turn out-of-class component
also into a social interaction!**

Perusall

every student prepared for every class



76 CHAPTER 4 MOMENTUM

In the preceding two chapters, we developed a mathematical framework for describing motion along a straight line. In this chapter, we continue our study of motion by investigating inertia, a property of objects that affects their motion. The experiments we carry out in studying inertia lead us to discover one of the most fundamental laws in physics—conservation of momentum.

4.1 Friction

Picture a block of wood sitting motionless on a smooth wooden surface. If you give the block a shove, it slides some distance but eventually comes to rest. Depending on the smoothness of the block and the smoothness of the wooden surface, this stopping may happen sooner or it may happen later. If the two surfaces in contact are very smooth and slippery, the block slides for a longer time interval than if the surfaces are rough. Notice that you have had this everyday experience: A hockey puck slides easily on ice but not on a rough road.

Figure 4.1 shows how the velocity of a wooden block decreases on three different surfaces. The slowing down is due to *friction*—the resistance to motion that one surface or object encounters when moving over another. Notice that, during the interval covered by the velocity-versus-time graph, the velocity decreases as the block slides over ice; it is hardly observable. The block slides easily over ice because there is very little friction between the two surfaces. The effect of friction is to bring two objects to rest with respect to each other—in this case the wooden block and the surface it is sliding on. The less friction there is, the longer it takes for the block to come to rest.

Figure 4.1 Velocity-versus-time graph for a wooden block sliding on three different surfaces. The rougher the surface, the more quickly the velocity decreases.



Figure 4.2 Low-friction track and carts used in the experiments described in this chapter.



You may wonder whether it is possible to make surfaces that have no friction at all, such that an object, once given a shove, continues to glide forever. There is no totally frictionless surface over which objects slide forever, but there are ways to minimize friction. You can, for instance, float an object on a cushion of air. This is most easily accomplished with a low-friction surface—like a smooth surface of water. The air serves as a cushion on which a conveniently shaped object can float, with friction between the object and the track all but eliminated. Alternatively, one can use wheeled carts with low-friction bearings on an ordinary track. Figure 4.2 shows low-friction carts you may have encountered in your lab or class. Although there is still some friction both for low-friction tracks and for the track shown in Figure 4.2, this friction is so small that it can be ignored during an experiment. For example, if the track in Figure 4.2 is horizontal, carts move along its length without slowing down appreciably. In other words:

In the absence of friction, objects moving along a horizontal track keep moving without slowing down.

Another advantage of using such carts is that the track constrains the motion to being along a straight line. We can then use a high-speed camera to record the cart's position at various instants, and from that information determine its speed and acceleration.



4.1 (a) Are the accelerations of the motions shown in Figure 4.1 constant? (b) For which surface is the acceleration largest in magnitude?

76 CHAPTER 4 MOMENTUM

In the preceding two chapters, we developed a mathematical framework for describing motion along a straight line. In this chapter, we continue our study of motion by investigating inertia, a property of objects that affects their motion. The experiments we carry out in studying inertia lead us to discover one of the most fundamental laws in physics—conservation of momentum.

4.1 Friction

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Figure 4.1 shows how the velocity of a wooden block decreases on three different surfaces. The slowing down is due to *friction*—the resistance to motion that one surface or object encounters when moving over another. Notice that the velocity decreases more rapidly on the rougher surface. The block slides easily over the smooth surface. To bring two objects to rest with no friction between the two surfaces, you would have to exert a force on them. In this case the wooden block and the surface are perfectly smooth. The less friction there is, the longer it takes for the block to come to rest.

Figure 4.1 Velocity-versus-time graph for a wooden block sliding on three different surfaces. The rougher the surface, the more quickly the velocity decreases.



Figure 4.2 Low-friction track and carts used in the experiments described in this chapter.



You may wonder whether it is possible to make surfaces that have no friction at all, such that an object, once given a shove, continues to glide forever. There is no totally frictionless surface over which objects slide forever, but there are ways to minimize friction. You can, for instance, float an object on a cushion of air. This is most easily accomplished with an air hockey table, in which the puck is cushioned with a thin layer of air that reduces friction. Alternatively, one can use wheeled carts with low-friction bearings on an ordinary track. Figure 4.2 shows low-friction carts you may have encountered in your physics lab. Although there is still some friction between the wheels and the track, it is so small that it can be neglected. For example, if the track is perfectly horizontal, the carts move along its length with constant velocity. In other words:

In the absence of friction, objects on a horizontal track keep moving without slowing down.

Another advantage of using such carts is that the track constrains the motion to being along a straight line. We can then use a high-speed camera to record the cart's position at various instants, and from that information determine its speed and acceleration.



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76 CHAPTER 4 MOMENTUM

In the preceding two chapters, we developed a mathematical framework for describing motion along a straight line. In this chapter, we continue our study of motion by investigating inertia, a property of objects that affects their motion. The experiments we carry out in studying inertia lead us to discover one of the most fundamental laws in physics—conservation of momentum.

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Figure 4.1 Velocity-versus-time graph for a wooden block sliding on three different surfaces. The rougher the surface, the more quickly the velocity decreases.



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You may wonder whether it is possible to make surfaces that have no friction at all, such that an object, once given a shove, continues to glide forever. There is no totally frictionless surface over which objects slide forever, but there are ways to minimize friction. You can, for instance, float an object on a cushion of air. This is most easily accomplished with a low-friction track—a track whose surface is dotted with little holes through which pressurized air blows. The air serves as a cushion on which a conveniently shaped object can float, with friction between the object and the track all but eliminated. Alternatively, one can use wheeled carts with low-friction bearings on an ordinary track. Figure 4.2 shows low-friction carts you may have encountered in your lab or class. Although there is still some friction both for low-friction tracks and for the track shown in Figure 4.2, this friction is so small that it can be ignored during an experiment. For example, if the track in Figure 4.2 is horizontal, carts move along its length without slowing down appreciably. In other words:

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Figure 4.1 shows how the velocity of a wooden block decreases on three different surfaces. The slowing down is due to *friction*—the force that opposes the motion of an object encountered during the interaction. In the velocity-versus-time graph, the velocity decreases as the block slides over ice is hardly observable. The block slides easily over ice because there is very little friction between the two surfaces. The effect of friction is to bring two objects to rest with respect to each other—in this case the wooden block and the surface it is sliding on. The less friction there is, the longer it takes for the block to come to rest.

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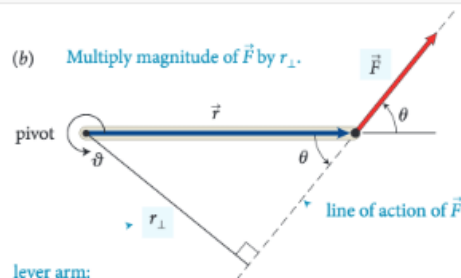
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Nov 1 4:41 pm



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(b) Multiply magnitude of \vec{F} by r_{\perp} .

lever arm:
perpendicular distance
from line of action of force to rotation axis (pivot)

action of the force and the axis of rotation. So, the torque caused by a force exerted on an object is the product of the magnitude of the force and its lever arm distance. It can be written equivalently as rF_{\perp} and as $r_{\perp}F$.

Like other rotational quantities, torque carries a sign that depends on the choice of direction for increasing ϑ . In Figure 12.4, for example, the torque caused by \vec{F}_1 about the pivot tends to rotate the rod in the direction of increasing ϑ and so is positive; the torque caused by \vec{F}_2 is negative. The sum of the two torques about the pivot is then $r_1F_1 + (-r_2F_2)$. As we've seen, the two torques are equal in magnitude when the rod is balanced, and so the sum of the torques is zero. When the sum of the torques is not zero, the rod's rotational acceleration is nonzero, and so its rotational velocity and angular momentum change.

In the situations depicted in Figures 12.4 and 12.5 we used the pivot to calculate the lever arm distances. This is a natural choice because that is the point about which the object under consideration is free to rotate. However, torques also play a role for stationary objects that are suspended or supported at several different points and that are not free to rotate—for example, a plank or bridge supported at either end. To determine what reference point to use in such cases, complete the following exercise.

Exercise 12.1 Reference point

Consider again the rod in Figure 12.4. Calculate the sum of the torques about the left end of the rod.

SOLUTION I begin by making a sketch of the rod and the three forces exerted on it, showing their points of application on the rod (Figure 12.6).

reference point

The lever arm distances must now be determined relative to the left end of the rod. The lever arm distance of force \vec{F}_1 to this point is zero, and so the torque caused by that force about the left end of the rod is zero. If I choose counterclockwise as the positive direction of rotation, \vec{F}_2 causes a negative torque about the left end of the rod; the force \vec{F}_{pr} exerted by the pivot causes a positive torque about the left end of the rod. The lever arm distance of \vec{F}_2 about the left end of the rod is $r_1 + r_2$; that of \vec{F}_{pr} is r_1 . Because the rod is at rest, the magnitude of the force exerted by the pivot is equal to the sum of the forces \vec{F}_1 and \vec{F}_2 . Taking into account the signs of the torques, we find that the sum of the torques about the left end of the rod is $r_1(F_1 + F_2) - (r_1 + r_2)F_2 = r_1F_1 - r_2F_2$. This is the same result we obtained for the torques about the pivot, and so the sum of the torques about the left end is zero. ✓

Exercise 12.1 shows that the sum of the torques about the left end of the rod is zero, just like the sum of the torques about the pivot. You can repeat the calculation for the torques about the right end of the rod or any other point, and each time you will find that the sum of the torques is zero. The reason is that the rod is not rotating about any point, and so the sum of the torques must be zero about any point. In general we can say:

For a stationary object, the sum of the torques is zero.

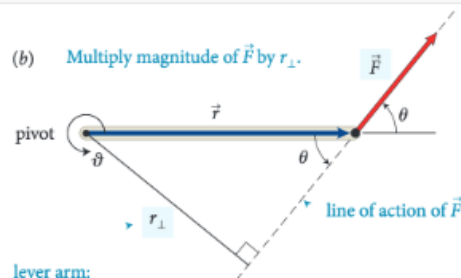
For a stationary object we can choose any reference point we like to calculate torques. It pays to choose a reference point that simplifies the calculation. As you have seen, we do not need to consider any force that is exerted at the reference point. So, by putting the reference point at the point of application of a force, we can eliminate that force from the calculation.



12.2 In the situation depicted in Figure 12.2a, you must continue to exert a force on the seesaw to keep the child off the ground. The force you exert causes a torque on the seesaw, and yet the seesaw's rotational acceleration is zero. How can this be if torques cause objects to accelerate rotationally?

Example 12.2 Torques on lever

Three forces are exerted on the lever of Figure 12.7. Forces \vec{F}_1 and \vec{F}_3 are equal in magnitude, and the magnitude of \vec{F}_2 is half as great. Force \vec{F}_1 is horizontal, \vec{F}_2 and \vec{F}_3 are vertical, and the lever makes an angle of 45° with the horizontal. Do these forces cause the lever to rotate about the pivot? If so, in which direction?

(b) Multiply magnitude of \vec{F} by r_{\perp} .

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? I think you may be able to think about the direction separately. So, after multiplying this magnitude and distance, you can attach a sign to the torque based on the defined parameters of the system. In the following paragraph, they start to explain how to choose this direction. Oct 20 12:38 am

? This is a great question. To further elaborate on this, we can think of this in terms of the Torque equation. The equation for torque is $\tau = r \times F$, with r being the level arm distance and F being force. We know that force is a vector vector from previous chapters, and in regards to "r" it can also be thought of as the radial vector. What this means is that this distance from the pivot points from the axis of rotation to the point where the force acts. In as previously mentioned, there is a general convention (the right-hand rule) that is used to determine the direction which happens to be perpendicular to both the radius from the axis and to the force. Oct 22 8:48 pm

Enter your comment or question and press Enter

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"helps me" flag



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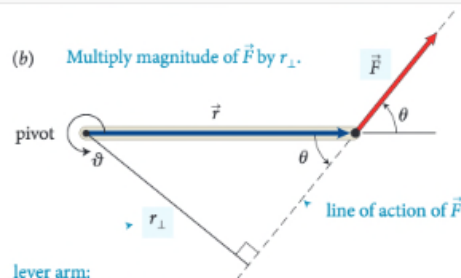
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+1 ✓

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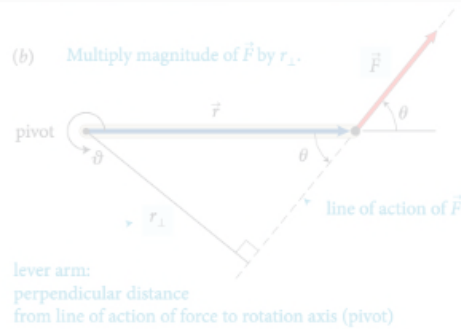
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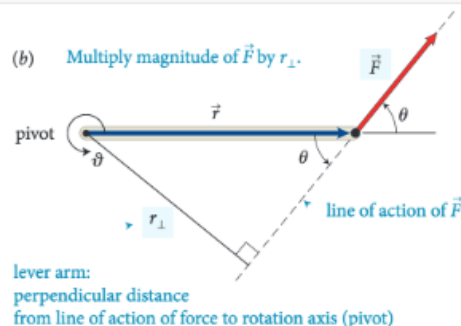
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Brian Lukoff responded to a question in Mazur Chapter 4 Sample that you wanted to know the answer to

21 minutes ago, you asked this question on Perusall:

No friction at all seems impossible. Isn't there always some friction in any real case?

Brian Lukoff just responded to the question by saying:

Right - I think there will always be some friction due to the second law of thermodynamics.

If this helps your understanding, click the button below. If you want to respond, simply reply to this email to post to Perusall.

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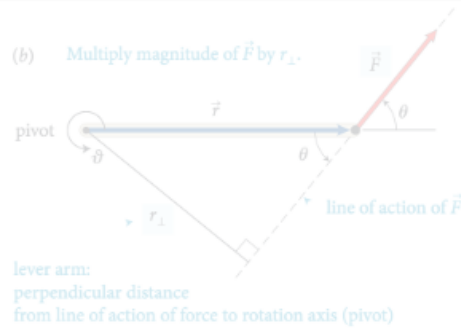
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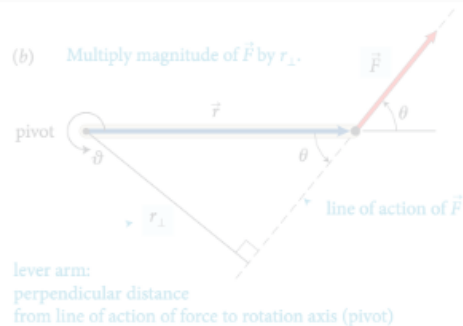
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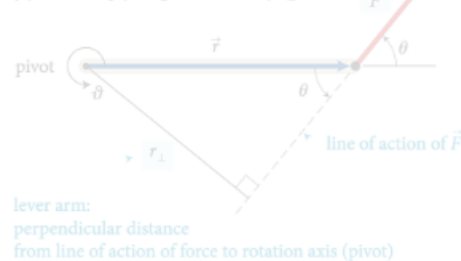
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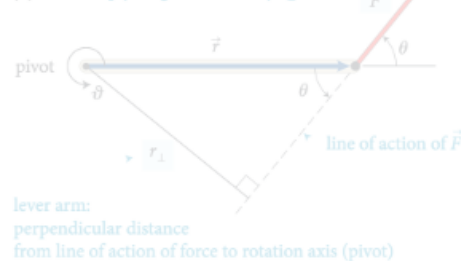
Enter your comment or question and press Enter

rubric-based assessment

must demonstrate thoughtful reading & interpretation

• quantity (10–20)

(b) Multiply magnitude of \vec{F} by r_{\perp} .



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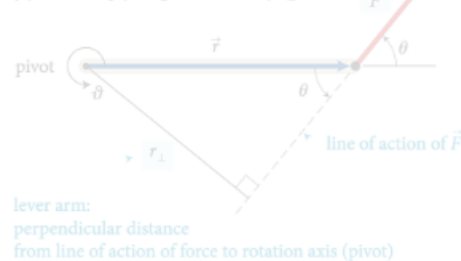
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rubric-based assessment

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lever arm:
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- timeliness (before class)

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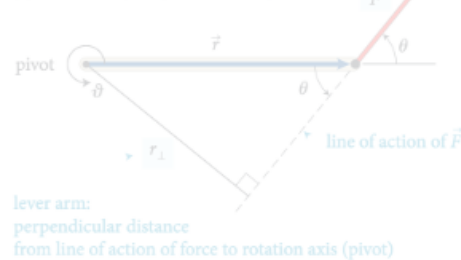
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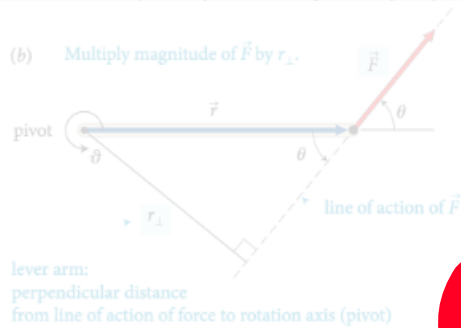
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lever arm:
perpendicular distance
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- quality (thoughtful reading & interpretation)

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over 20,000 annotations!

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For a rotating object, we choose a reference point that is fixed relative to the object. We then calculate the torque about this point. As you have seen, we do not need to know the position of the reference point relative to the object. The only thing that matters is the position of the reference point relative to the point of application of the force. The torque about the reference point is $\tau = r_{\perp} F$, where r_{\perp} is the perpendicular distance from the reference point to the line of action of the force.

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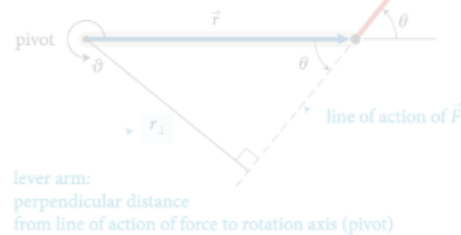
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rubric-based assessment

(b) Multiply magnitude of \vec{F} by r_{\perp} .



- quality (though future could interpret)

• quantity (you minimize)

- timeliness (before class)

- distribution (not clustered)

The lever arm distances must now be determined relative to the left end of the rod. The lever arm distance of force \vec{F}_1 about the left end of the rod is zero, and so the torque caused by that force about the left end of the rod is zero. If I choose counter-clockwise as the positive direction of rotation, \vec{F}_2 is a negative torque about the left end of the rod (it tends to rotate the rod clockwise) and causes a positive torque about the right end of the rod. The lever arm distance of \vec{F}_2 about the left end of the rod is r_2 . The lever arm distance of \vec{F}_3 about the left end of the rod is r_3 . The sum of the torques about the left end of the rod is $(\vec{F}_1 + \vec{F}_2 + \vec{F}_3) \cdot \vec{r}$. This is the same result obtained for the torques about the pivot, and so the sum of the torques about the left end is zero. ✓

Exercise 12.1 shows that the sum of the torques about the left end of the rod is zero, just like the sum of the torques about the pivot. You can repeat the calculation for the right end of the rod and find that the sum of the torques about the right end is also zero. The reason is that the sum of the torques about any point is zero. In general, the sum of the torques about any point is zero.

For a static equilibrium problem, you must choose a reference point to calculate the torques. As you have seen, we do not need to consider any force that is exerted at the reference point. So, by putting the reference point at the point where a force is exerted, we can eliminate that force from the calculation.



12.2 In the situation depicted in Figure 12.2a, you must continue to exert a force on the seesaw to keep the child off the ground. The force you exert causes a torque on the seesaw, and yet the seesaw's rotational acceleration is zero. How can this be if torques cause objects to accelerate rotationally?

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Three forces are exerted on the lever of Figure 12.7. Forces \vec{F}_1 and \vec{F}_2 are equal in magnitude, and the magnitude of \vec{F}_3 is half as great. Force \vec{F}_1 is horizontal, \vec{F}_2 and \vec{F}_3 are vertical, and the lever makes an angle of 45° with the horizontal. Do these forces cause the lever to rotate about the pivot? If so, in which direction?

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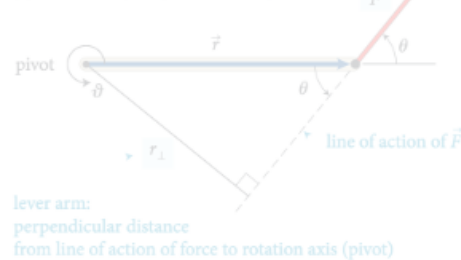
Objects executing motion ar...

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fully automated assessment

(b) Multiply magnitude of \vec{F} by r_{\perp} .



- specialized machine learning algorithm
- assesses intellectual content
- exceeds intercoder reliability

I don't understand how this combination of factors tells you anything about direction? Aren't magnitude and lever arm distance both scalar quantities? It seems like you would have to know some sort of direction to calculate torque.

Oct 20 12:09 am

I think you may be able to think about the direction separately. So, after multiplying this magnitude and distance, you can attach a sign to the torque based on the defined parameters of the system. The sign convention is arbitrary, but you can explain how to choose it.

Oct 20 12:38 am

This is a great question. To further elaborate on this, we can think of this in terms of the Torque equation. The equation for torque is $\tau = r \times F$, with r being the level arm distance and F being force. We know that force is a vector vector from previous chapters, and in regards to " r " it can also be thought of as the radial vector. What this means is that this distance from the pivot points from the axis of rotation to the point where the force acts. In as previously mentioned, there is a general convention (the right-hand rule) that is used to determine the direction which happens to be perpendicular to both the radius from the axis and to the force.

Oct 22 8:48 pm

Enter your comment or question and press Enter

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For a stationary object, the sum of the torques is zero.

For a stationary object we can choose any reference point. We like to choose the pivot point, but we can choose a reference point that is not the pivot. In fact, you have seen, we do not need to consider any force that is exerted at the reference point. So, by putting the reference point at the point of application of a force, we can eliminate that force from the calculation.



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Total number of annotations **16**

Total number of annotations submitted on time **11**

Average quality of top 10 annotations submitted on time **1.80**

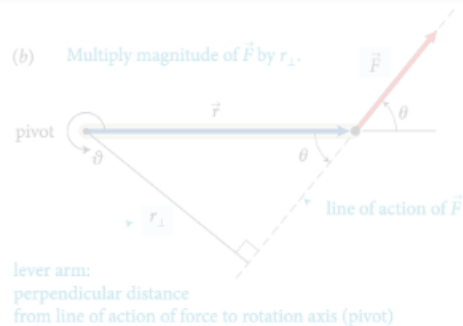
2 = demonstrates thorough and thoughtful reading and insightful interpretation of the reading, 1 = demonstrates reading, but no (or only superficial) interpretation of the reading, 0 = does not demonstrate any thoughtful reading or interpretation

Distribution of annotations **3.8**

0 = clustered, 5 = evenly distributed throughout assignment

Assignment score **1**

scores range from 0 to 3

(b) Multiply magnitude of \vec{F} by r_{\perp} .

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perpendicular distance
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connect pre-class and in-class activities

I don't think you can calculate torque without knowing the direction of the force. Even if you know the magnitude of the force, you need to know the direction of the force to calculate the lever arm distance both scalar quantities? It seems like we would need to know some sort of direction to calculate torque.

I think you may be able to think about the direction separately. So, after multiplying this magnitude and distance, you can attach a sign to the torque based on the defined parameters of the system. In the following paragraph, they start to explain how to choose this direction.

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Confusion report for Chapter 24

right hand rule (11 questions)

- JB Can someone in simpler terms explain the right- hand rule? +1
- WJ Is there another way, besides the right hand rule, to find the direction of the magnetic field with a current?
- SB Using the right hand rule, I believe the answer is D. Is that correct? Show more...

direction magnetic field (8 questions)

- CP Why is it that the magnet field points away from the north pole and towards the south pole? When on the previous page it stated that the direction of the magnetic field is the direction that the north pole of a compass needle points. +2
- AB How can you determine which direction the magnetic field will point towards? +1
- KH So whichever way the north pole faces is the direction of the magnetic field but that doesn't always mean its pointing true north? +1 Show more...

earth magnetic field (6 questions)

- CP Does that mean that the compass will be distracted from the Earth's magnetic field and use the magnetic field that the current of the wire gives off?
- AK Can someone explain why this type of bacteria knows what direction the earth's magnetic fields are facing?
- J Does the circular loop of current have any similarities with the look of the earths magnetic field? They kind of look similar to me. Show more...

motivating factors

Intrinsic:

• social interaction

(b) Multiply magnitude of \vec{F} by r_{\perp} .



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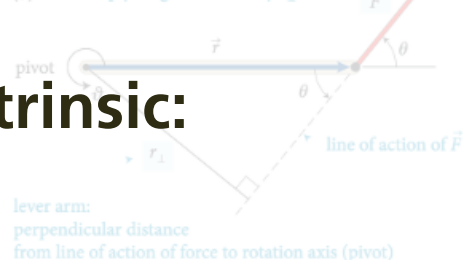
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motivating factors

Intrinsic:

- social interaction
- tie-in to in-class activity

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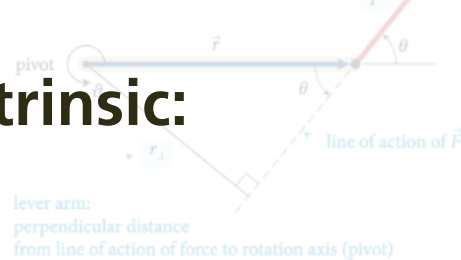
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- assessment (fully automated)

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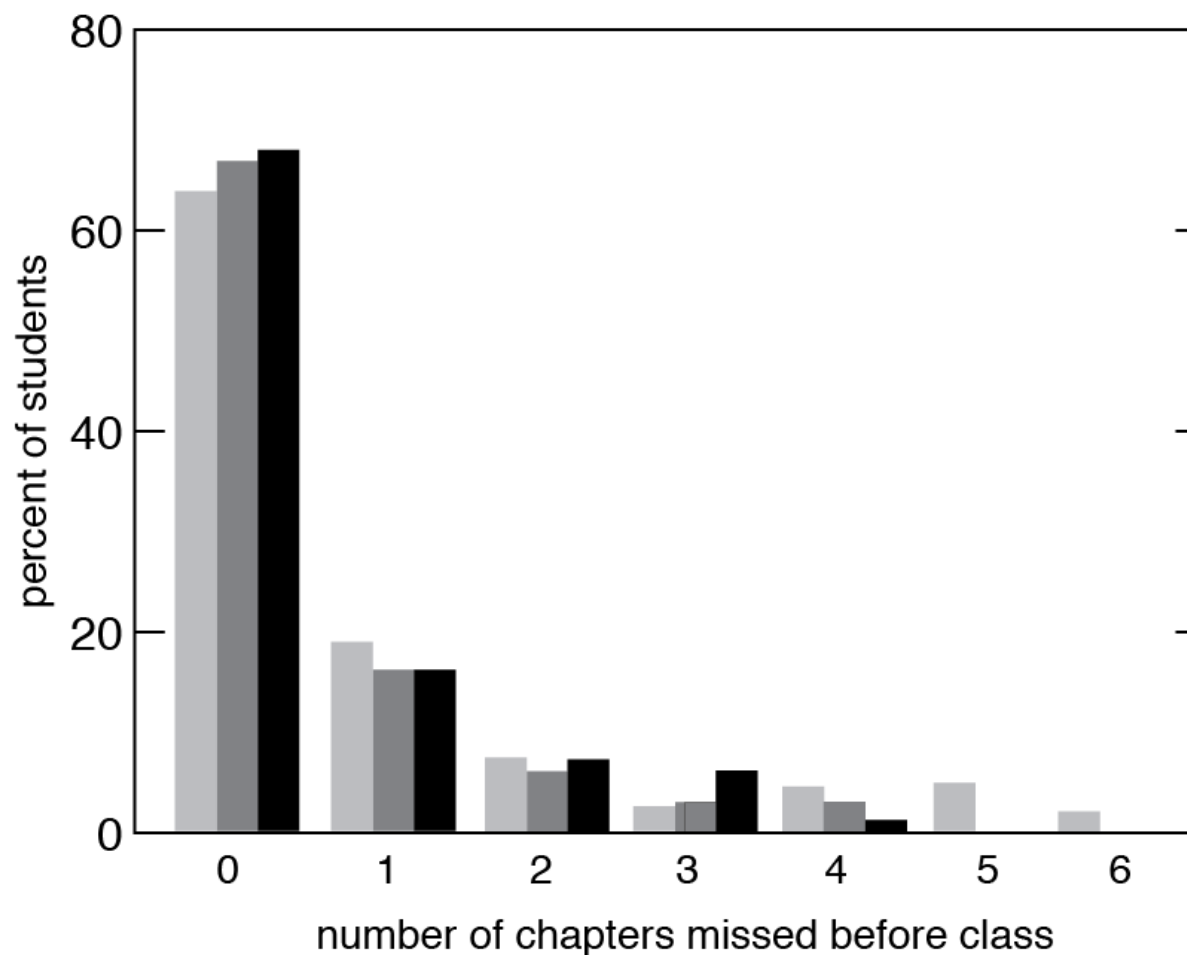
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(b) Multiply magnitude of \vec{F} by r_{\perp} .

\vec{F}

reference point

The lever arm distances must now be determined relative to the left end of the rod. The lever arm distance of force \vec{F}_1 to this



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This is a great question. I can think of this in terms of torque is $\tau = r \times F$, with r the lever arm distance. We know that force is in regards to "r" it can also mean is that this distance is to the point where the force is applied. The general convention (the right-hand rule) is that the direction which happens to be perpendicular to both the radius from the axis and to the force.

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Example 12.2 Torques on lever

Three forces are exerted on the lever of Figure 12.7. Forces \vec{F}_1 and \vec{F}_3 are equal in magnitude, and the magnitude of \vec{F}_2 is half as great. Force \vec{F}_1 is horizontal, \vec{F}_2 and \vec{F}_3 are vertical, and the lever makes an angle of 45° with the horizontal. Do these forces cause the lever to rotate about the pivot? If so, in which direction?

research data

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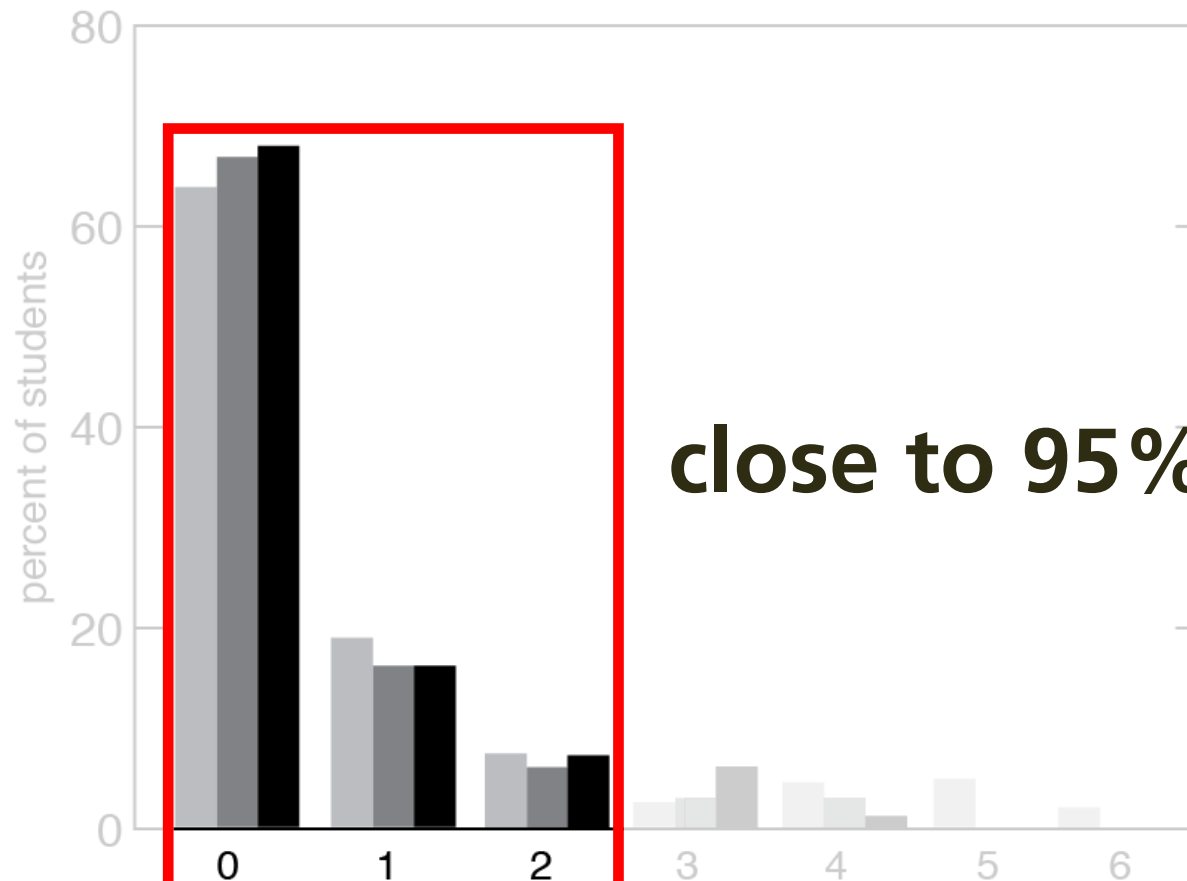
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close to 95%!

number of chapters missed before class

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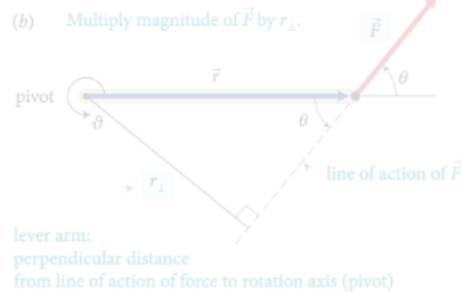
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The lever arm distances must now be determined relative to the left end of the rod. The lever arm distance of force \vec{F}_1 to this point is zero, and so the torque caused by that force about the left end of the rod is zero. If I choose counterclockwise as the positive direction of rotation, \vec{F}_2 causes a negative torque about the left end of the rod; the force \vec{F}_{pr} exerted by the pivot causes a positive torque about the left end of the rod. The lever arm distance of \vec{F}_2 about the left end of the rod is $r_1 + r_2$; that of \vec{F}_{pr} is r_1 . Because the rod is at rest, the magnitude of the force exerted by the pivot is equal to the sum of the forces \vec{F}_1 and \vec{F}_2 . Taking into account the signs of the torques, we find that the sum of the torques about the left end of the rod is $r_1(F_1 + F_2) - (r_1 + r_2)F_2 = r_1F_1 - r_2F_2$. This is the same result we obtained for the torques about the pivot, and so the sum of the torques about the left end is zero. ✓

Exercise 12.1 shows that the sum of the torques about the left end of the rod is zero, just like the sum of the torques about the pivot. You can repeat the calculation for the right end of the rod and find that the sum of the torques is also zero. The reason is that the rod is not rotating about any point, and so the sum of the torques must be zero about any point. In general we can say:

For a stationary object, the sum of the torques is zero.

For a stationary object we can choose any reference point we like to calculate torques. It pays to choose a reference point that simplifies the calculation. As you have seen, we do not need to consider any force that is exerted at the reference point. So, by putting the reference point at the point of application of a force, we can eliminate that force from the calculation.



12.2 In the situation depicted in Figure 12.2a, you must continue to exert a force on the seesaw to keep the child off the ground. The force you exert causes a torque on the seesaw, and yet the seesaw's rotational acceleration is zero. How can this be if torques cause objects to accelerate rotationally?

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every student prepared for every class

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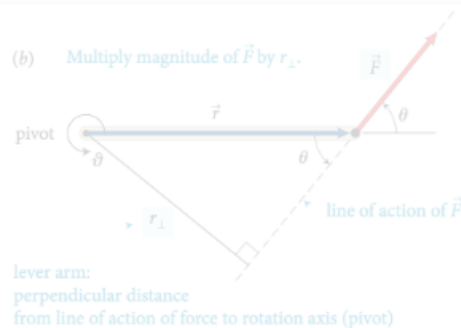
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I don't understand how this combination of... Oct 20 12:09 am

I think you may be able to think about the direction separately. So, after multiplying this magnitude and distance, you can attach a sign to the torque based on the defined parameters of the system. In the following paragraph, they start to explain how to choose this direction. Oct 20 12:38 am

This is a great question. To further elaborate on this, we can think of this in terms of the Torque equation. The equation for torque is $\tau = r \times F$, with r being the level arm distance and F being force. We know that force is a vector vector from previous chapters, and in regards to "r" it can also be thought of as the radial vector. What this means is that this distance from the pivot points from the axis of rotation to the point where the force acts. In as previously mentioned, there is a general convention (the right-hand rule) that is used to determine the direction which happens to be perpendicular to both the radius from the axis and to the force. Oct 22 8:48 pm

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action of the force and the axis of rotation. So, the torque caused by a force exerted on an object is the product of the magnitude of the force and its lever arm distance. It can be

Let's do a live demo together

? I don't understand how this combination of factors tells you anything about direction? Aren't magnitude and lever arm distance both scalar quantities? It seems like we would need to know some sort of direction to calculate torque.

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reference point

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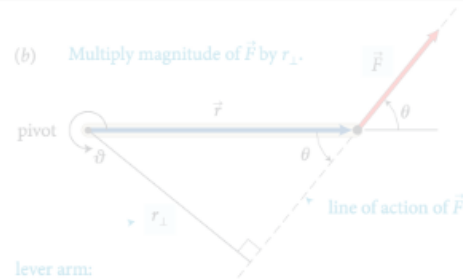
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lever arm:
perpendicular distance
from line of action of force to rotation axis (pivot)

action of the force and the axis of rotation. So, the torque caused by a force exerted on an object is the product of the magnitude of the force and its lever arm distance. It can be written equivalently as rF_{\perp} and as $r_{\perp}F$.

Like other rotational quantities, torque carries a sign that depends on the choice of direction for increasing θ . In Figure 12.4, for example, the torque caused by \vec{F}_1 about the pivot tends to rotate the rod in the direction of increasing θ and so is positive; the torque caused by \vec{F}_2 is negative. The sum of the two torques about the pivot is then $r_1F_1 + (-r_2F_2)$. As we've seen, the two torques are in magnitude, and the sum of the two torques is zero. The rod's rotational acceleration is zero, and so its rotational velocity and angular momentum change.

In the situations depicted in Figures 12.4 and 12.5 we used the pivot to calculate the lever arm distances. This is a natural choice because that is the point about which the object under consideration is free to rotate. However, torques also play a role for stationary objects that are suspended or supported at several different points and that are not free to rotate—for example, a plank or bridge supported at either end. To determine what reference point to use in such cases, complete the following exercise.

Exercise 12.1 Reference point

Consider again the rod in Figure 12.4. Calculate the sum of the torques about the left end of the rod.

SOLUTION I begin by making a sketch of the rod and the three forces exerted on it, showing their points of application on the rod (Figure 12.6).

reference point

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Exercise 12.1 shows that the sum of the torques about the left end of the rod is zero, just like the sum of the torques about the pivot. You can repeat the calculation for the torques about the right end of the rod or any other point, and each time you will find that the sum of the torques is zero. The reason is that the rod is not rotating about any point, and so the sum of the torques must be zero about any point. In general we can say:

The sum of the torques about any point is zero. This is a useful result, and it is often used to calculate torques. It pays to choose a reference point that simplifies the calculation. As you have seen, we do not need to consider any force that is exerted at the reference point. So, by putting the reference point at the point of application of a force, we can eliminate that force from the calculation.



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follow up questions?
support@perusall.com