Flat space, deep learning

Pontificia Universidad Católica de Chile
Santiago, Chile, 15 January 2016

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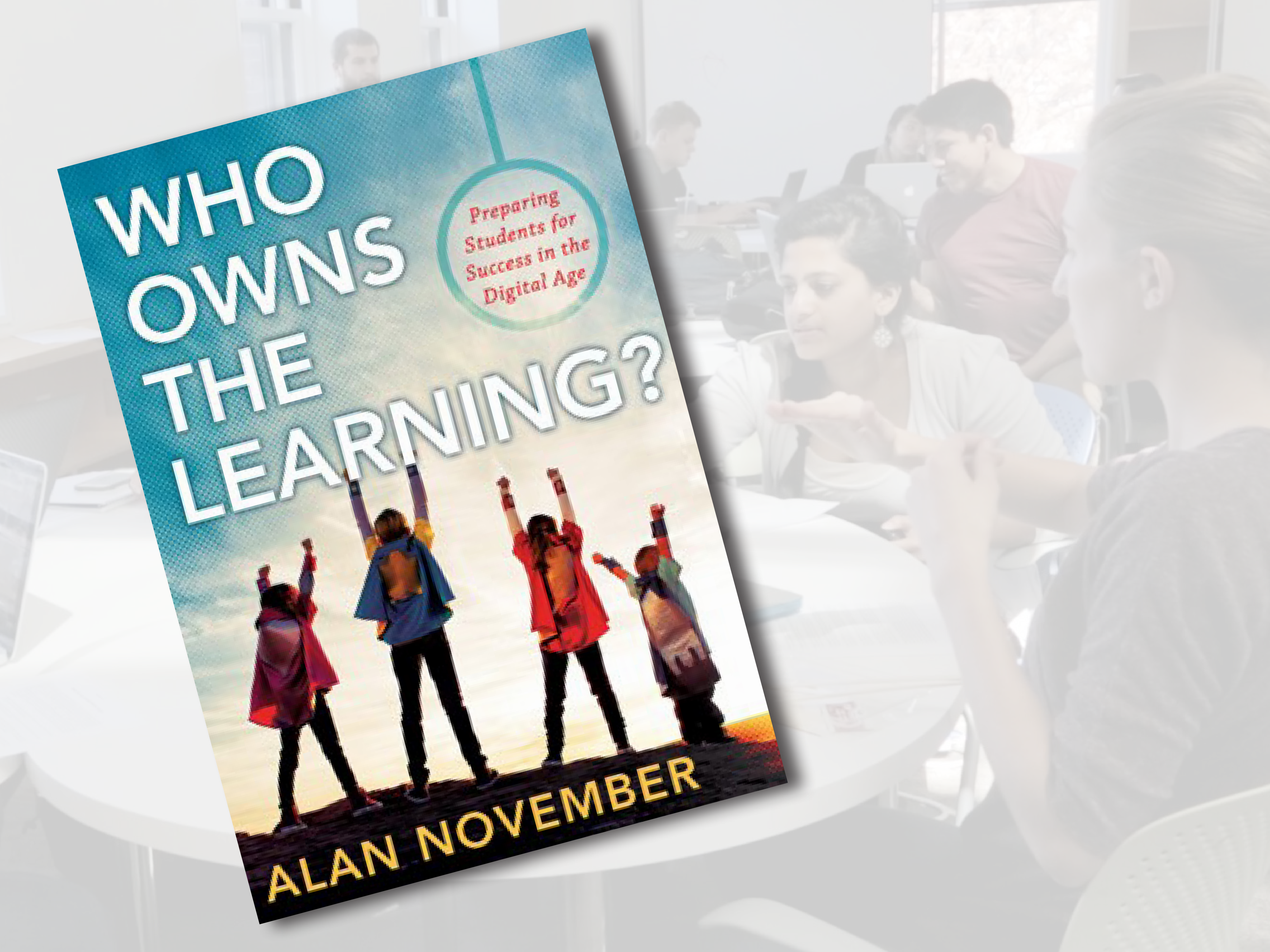
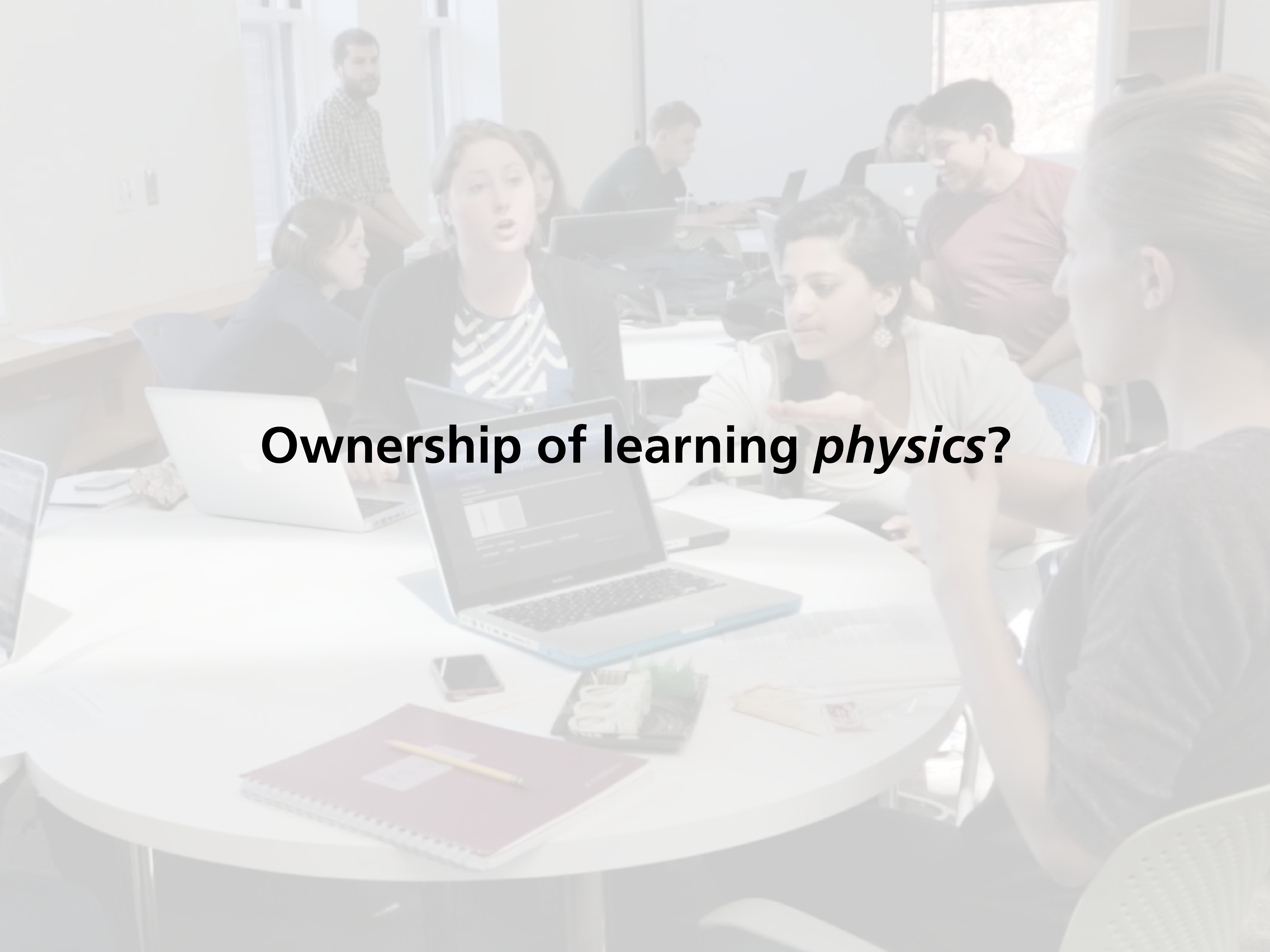
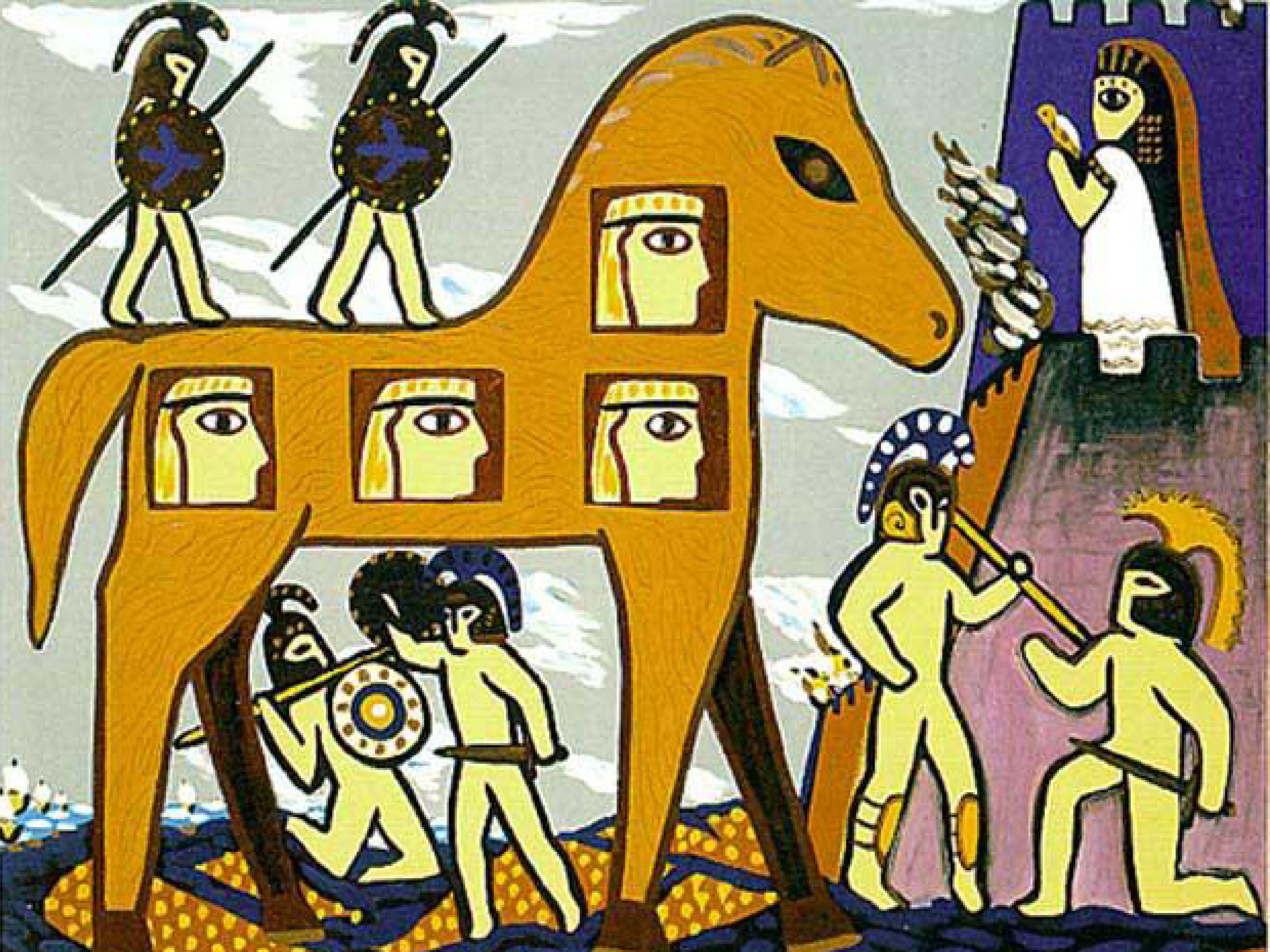

WHO OWNS THE LEARNING?
Preparing Students for Success in the Digital Age
ALAN NOVEMBER

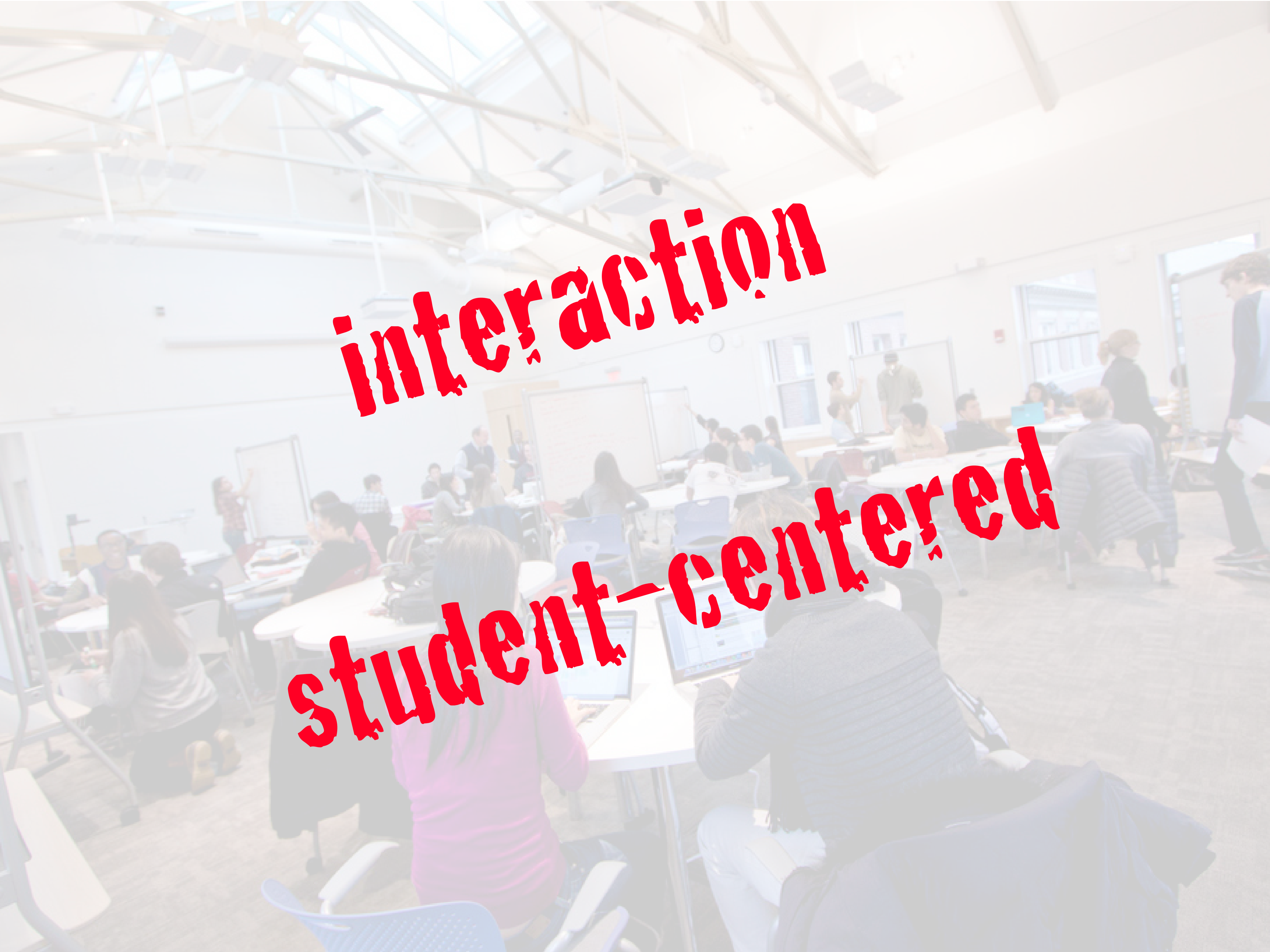


Ownership of learning *physics*?



team & project-based approach


information transfer
faculty-centered


interaction
student-centered


no lectures
no exams

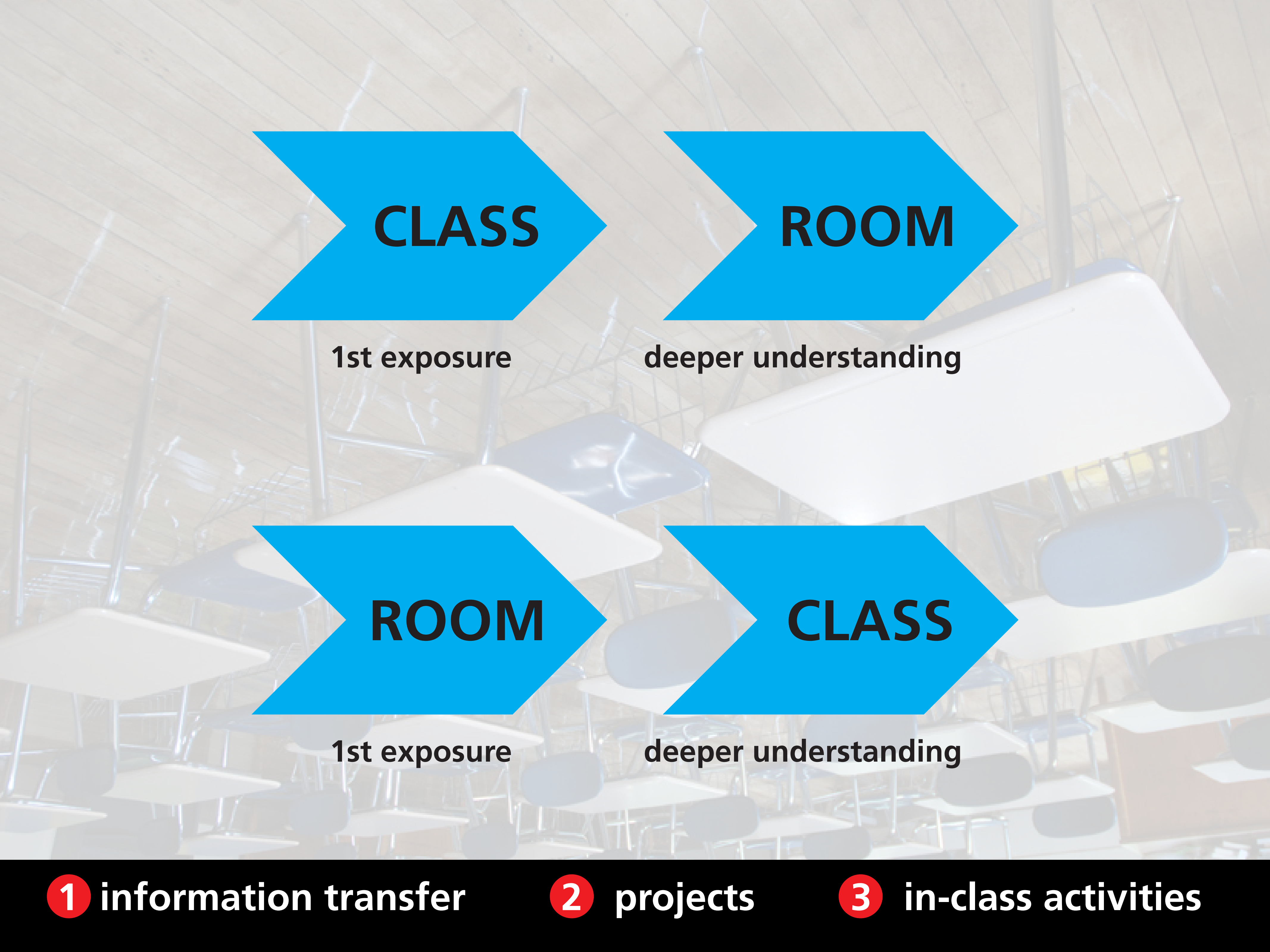
CLASS → **ROOM**

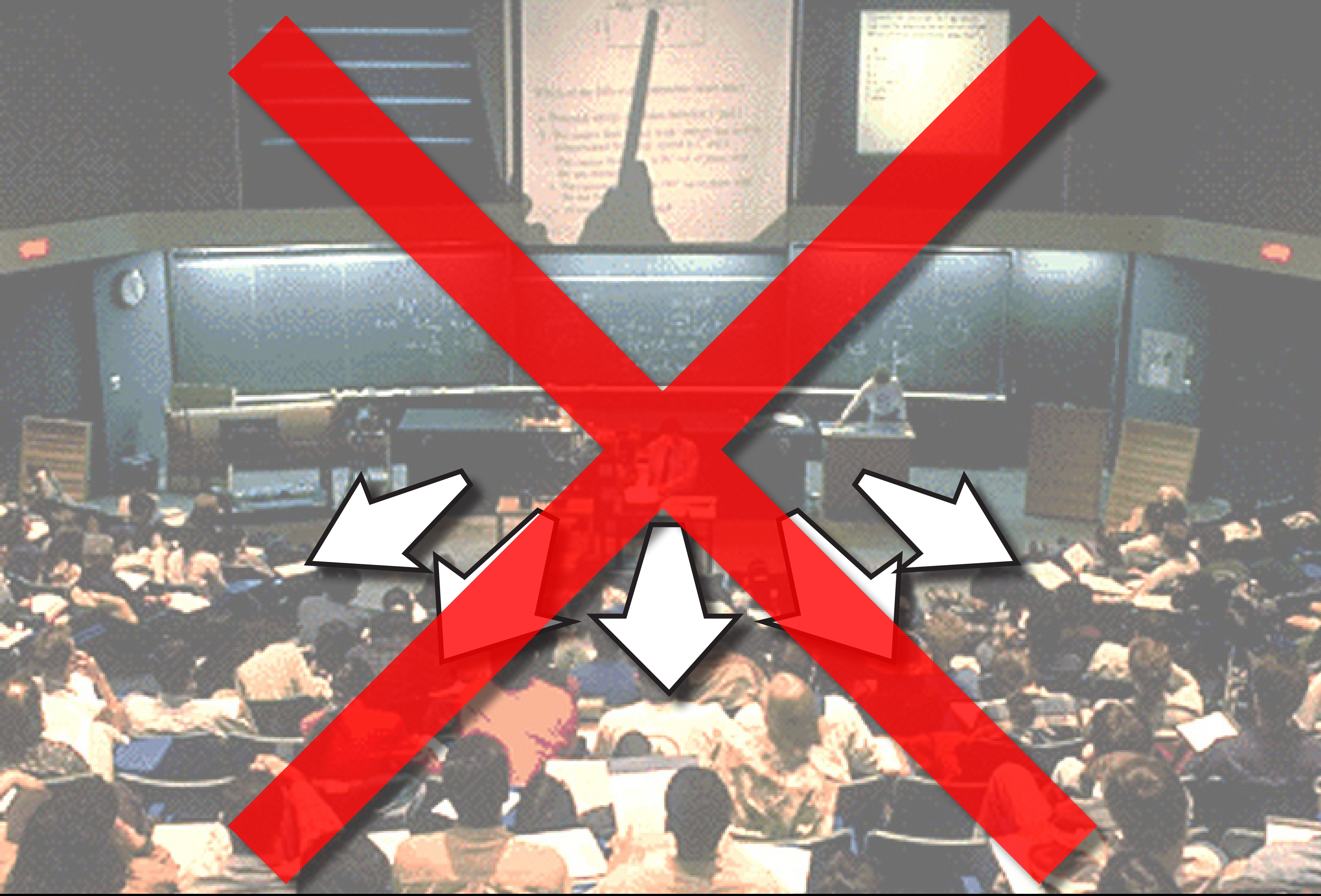
1st exposure → deeper understanding


CLASS
ROOM
1st exposure
deeper understanding
ROOM
CLASS
1st exposure
deeper understanding

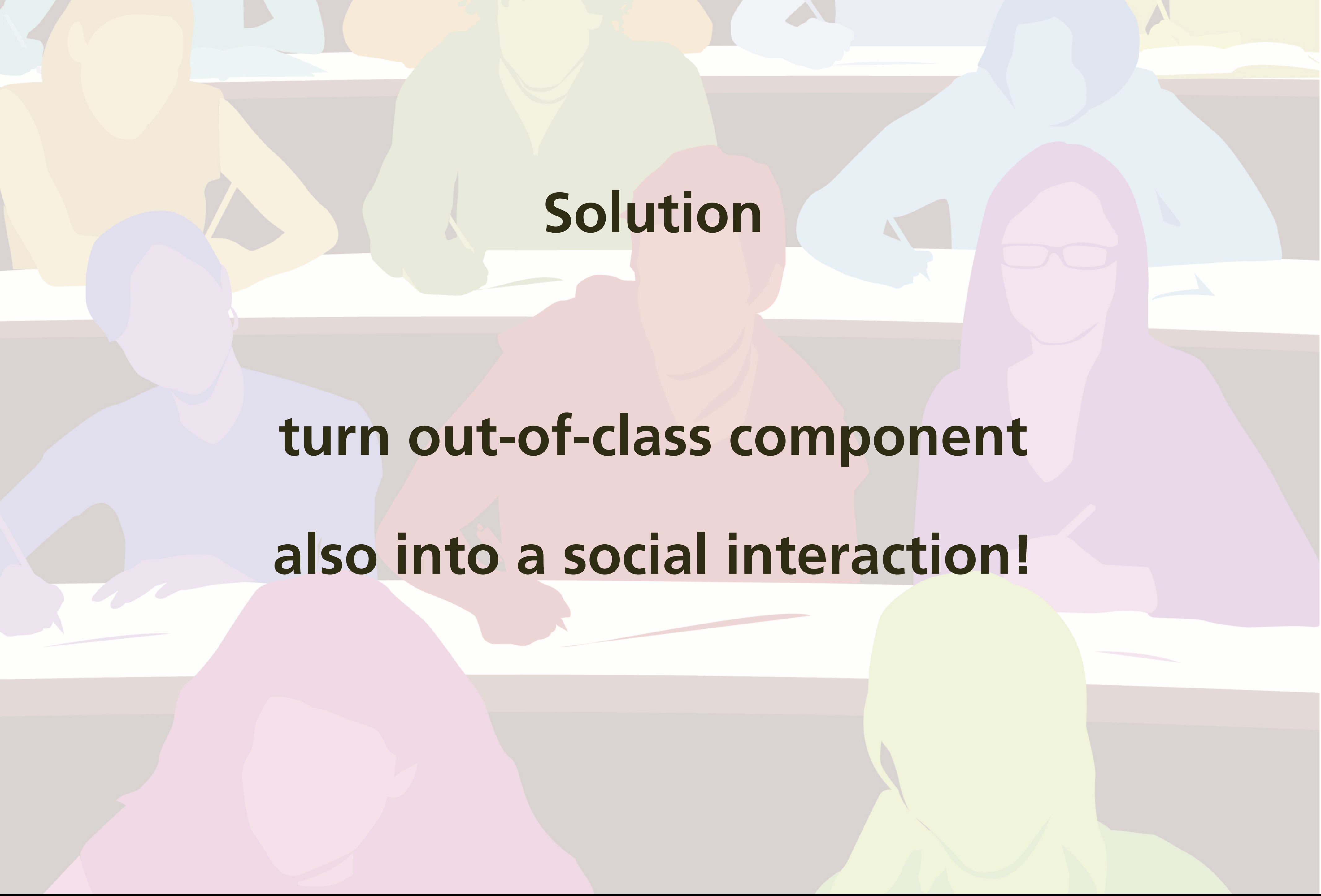
1 information transfer

1 information transfer 2 projects


CLASS
ROOM
1st exposure
deeper understanding
ROOM
CLASS
1st exposure
deeper understanding
1 information transfer
2 projects
3 in-class activities



1 information transfer

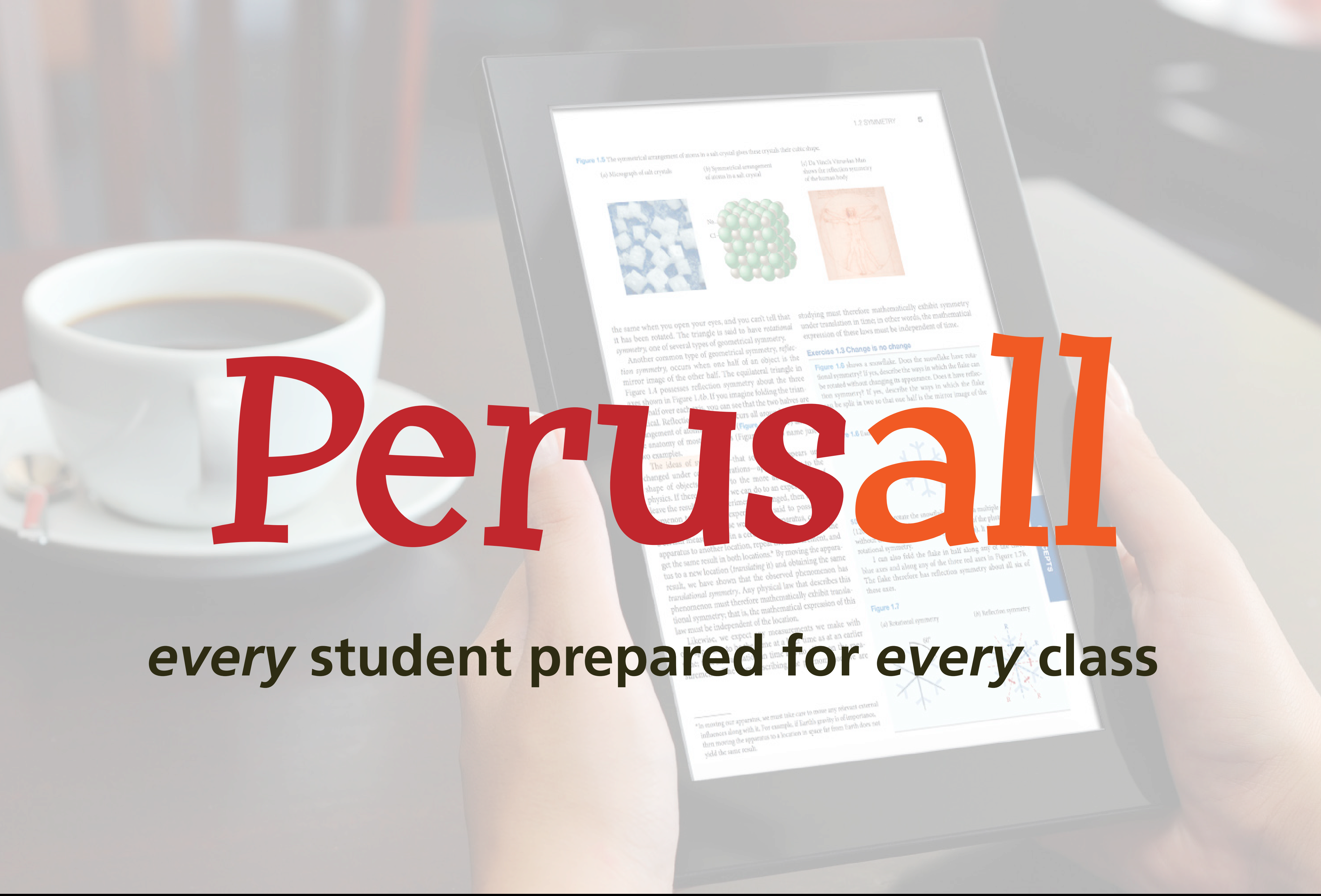


Solution

turn out-of-class component

also into a social interaction!

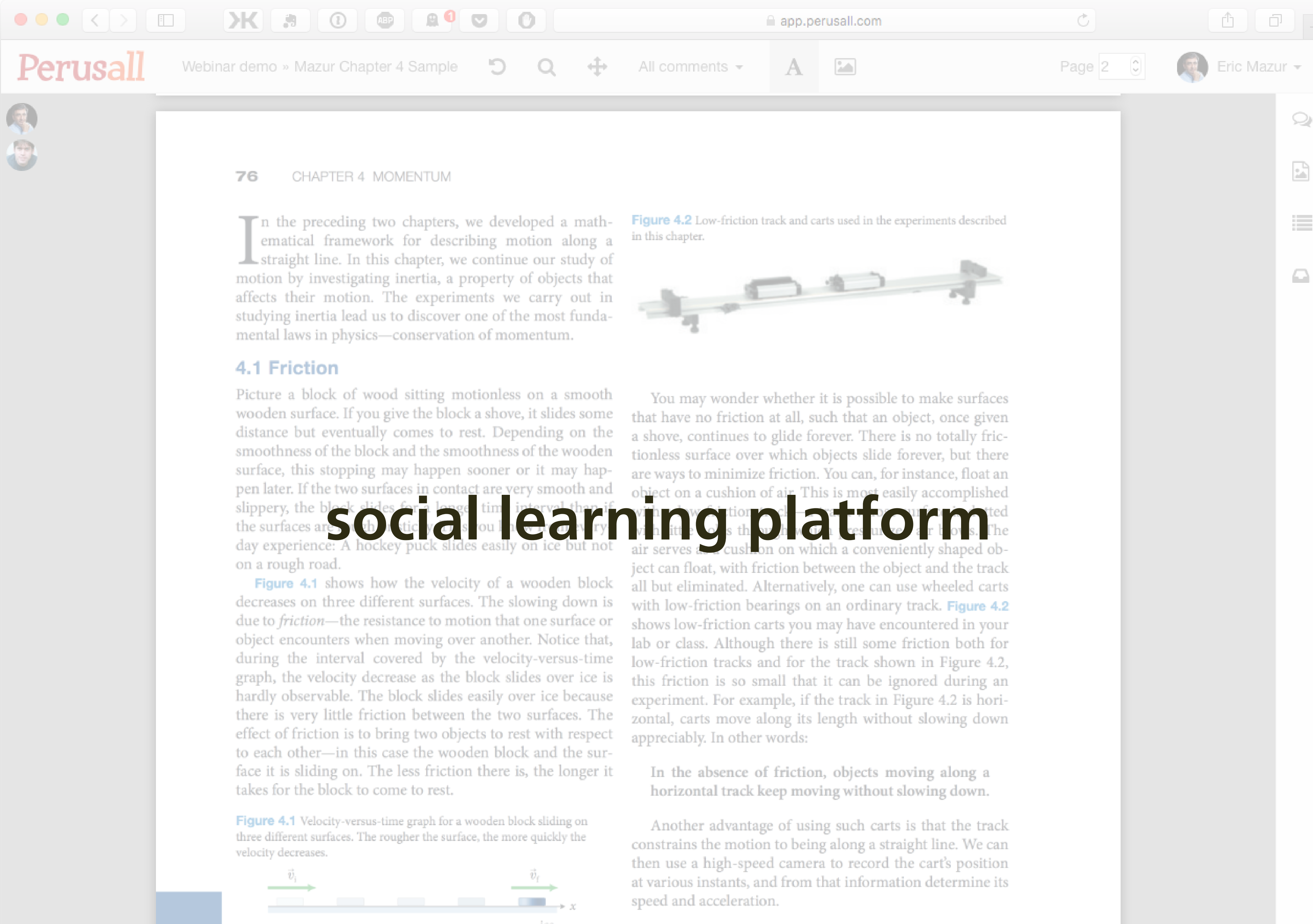
1 information transfer



Perusall

every student prepared for *every* class

1 information transfer



1 information transfer

1 design

2 approach

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Perusall Webinar demo » Mazur Chapter 4 Sample All comments Page 2 Eric Mazur

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 or sticky. This you know from 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 decrease 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.

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.

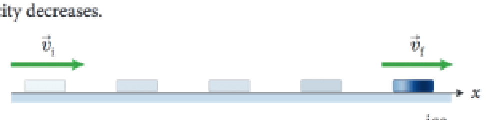
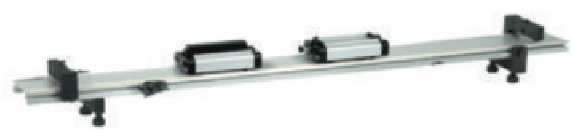


Figure 4.2 Low-friction track and carts used in the experiments described in this chapter.

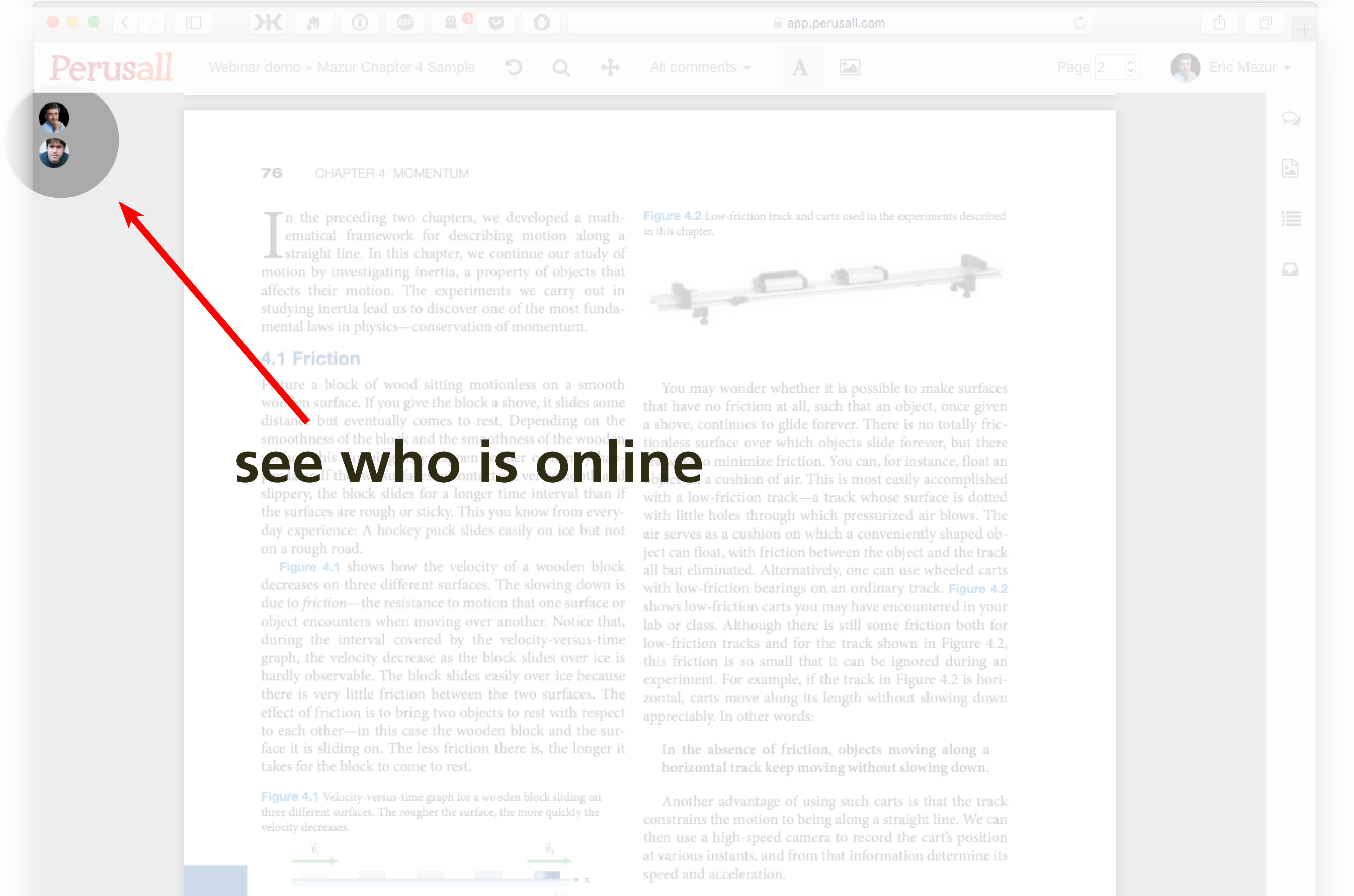


You may wonder whether it is possible to make surfaces that have no friction at all, such that an object, once given a shove, continues to glide forever. There is no totally frictionless surface over which objects slide forever, but there are ways to minimize friction. You can, for instance, float an object on a cushion of air. This is most easily accomplished with a low-friction 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:

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.

1 information transfer



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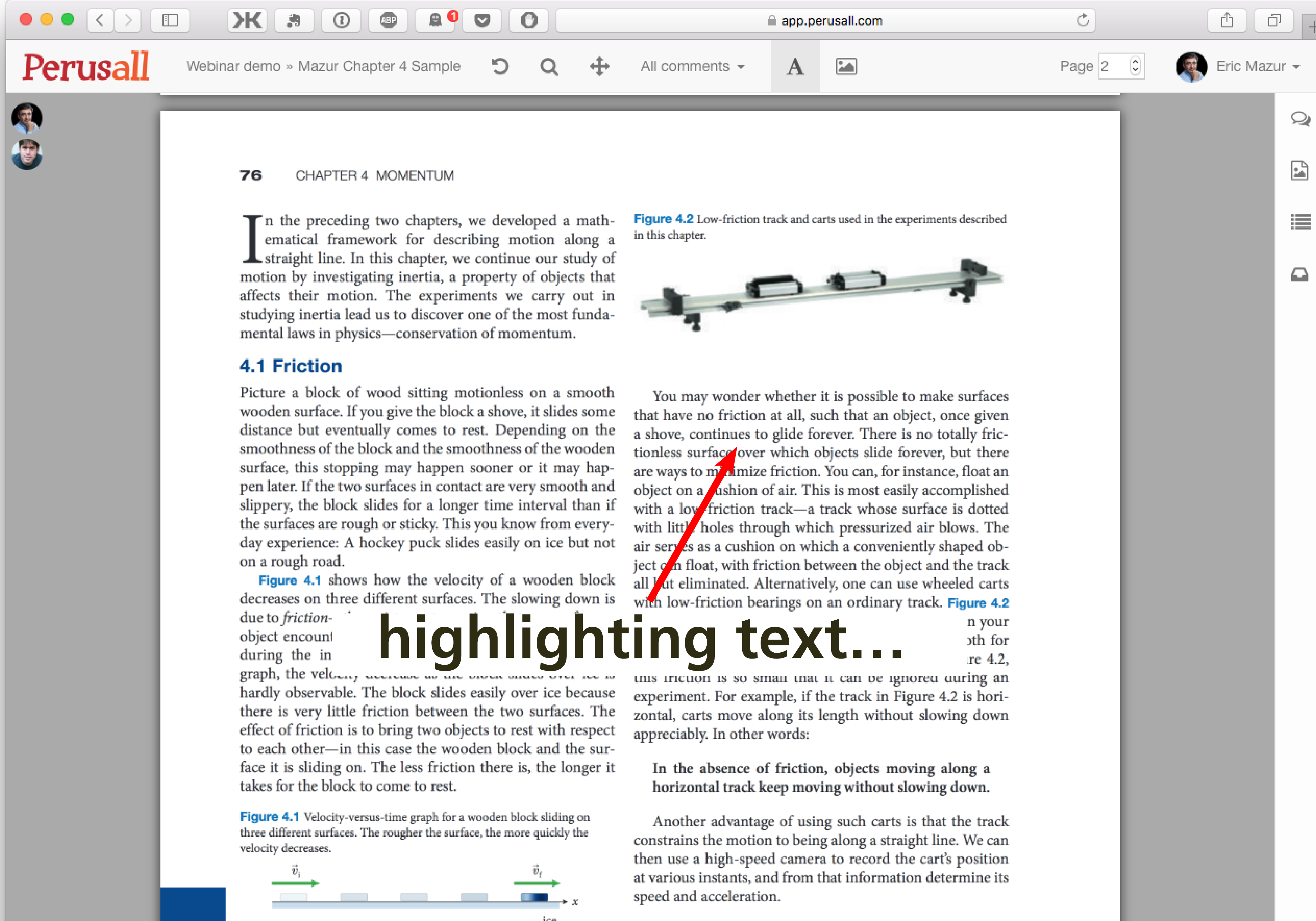

76 CHAPTER 4 MOMENTUM

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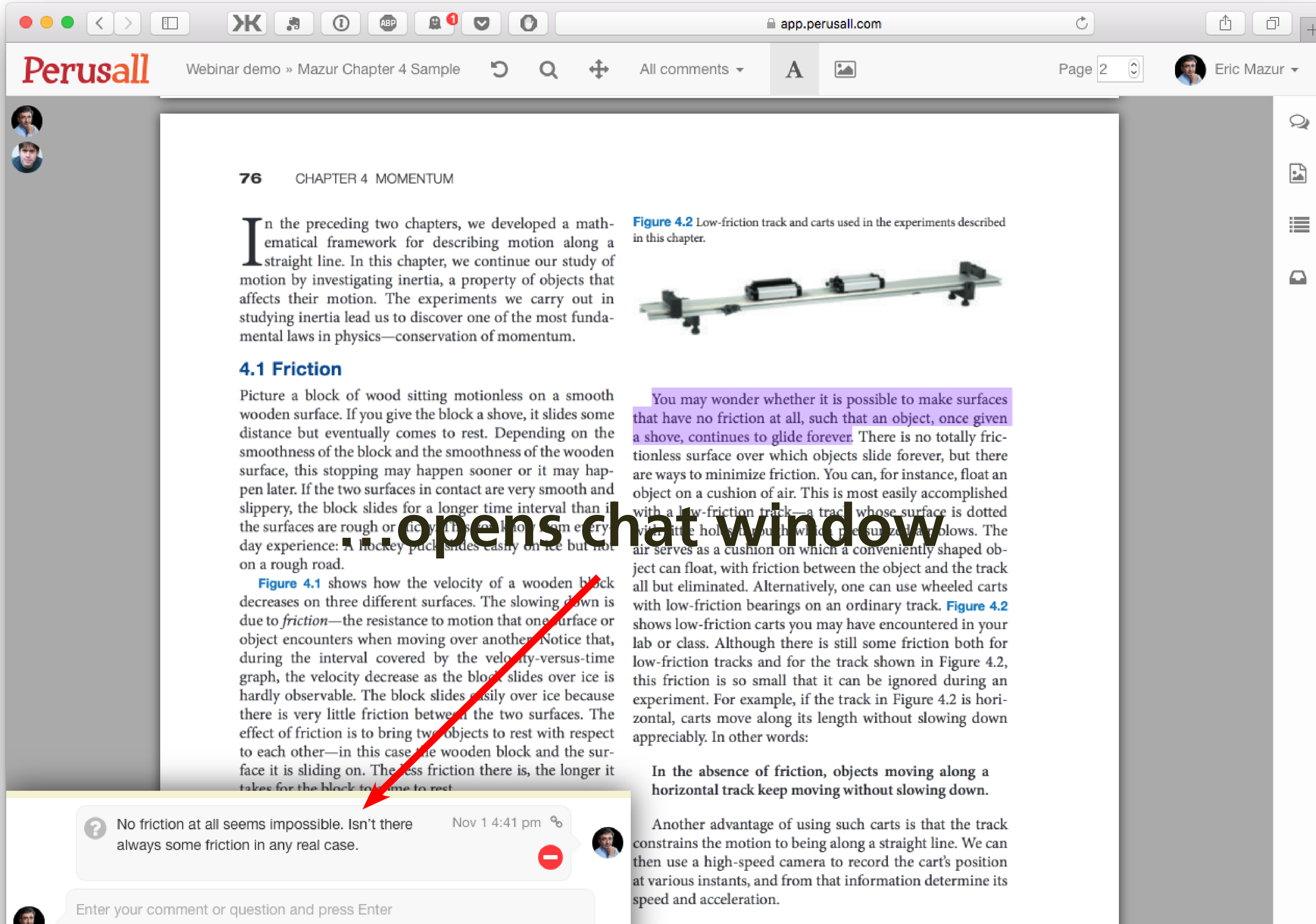
1 information transfer



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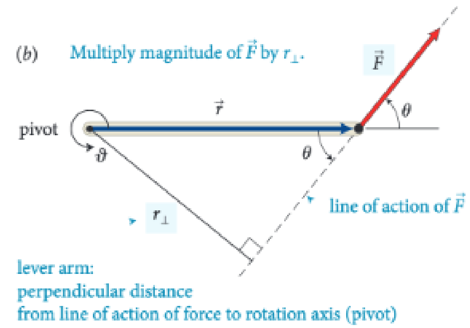
1 information transfer



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.

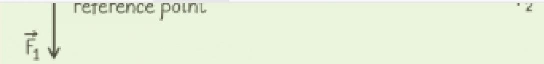
In the situations depicted in Figures 12.4 and 12.5 we used the pivot to calculate the lever arm distances. This is a natural choice because that is the point about which the object under consideration is free to rotate. However, torques also play a role for stationary objects that are suspended or supported 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.

CONCEPTS

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



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 $\vec{F}^c_{pr}$ 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 $\vec{F}^c_{pr}$ 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 12.2*a*, 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

1 information transfer

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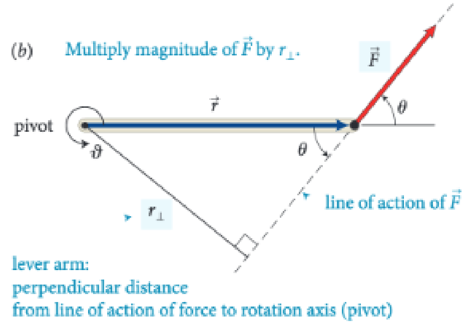
Perusall AP50 Fall 2015 » Chapter 12 Group 1's comments Page 284 Eric Mazur



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

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. — Oct 20 12:09 am

SB: 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 τ = r X 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

reference point

$\vec{F}_1$

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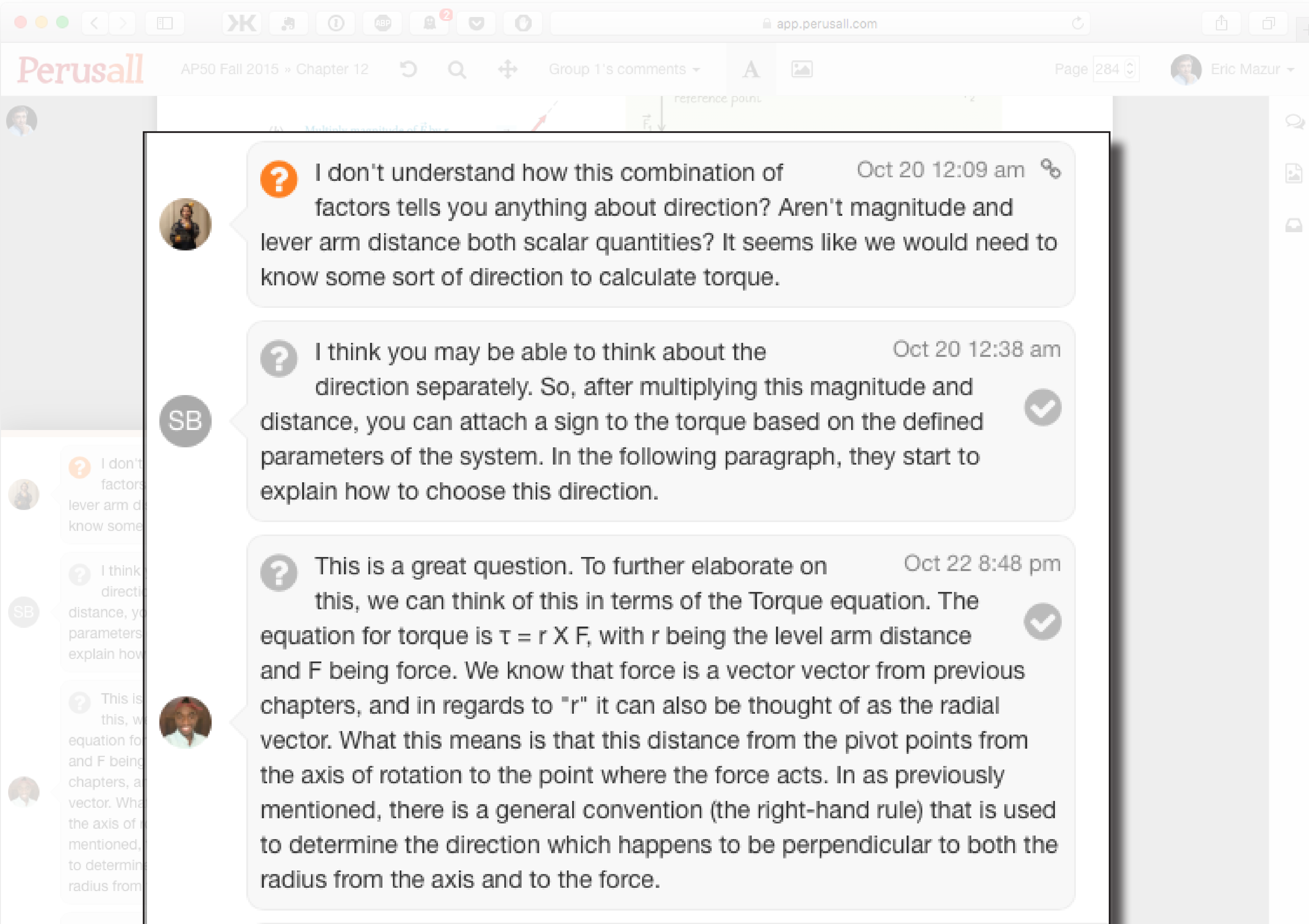
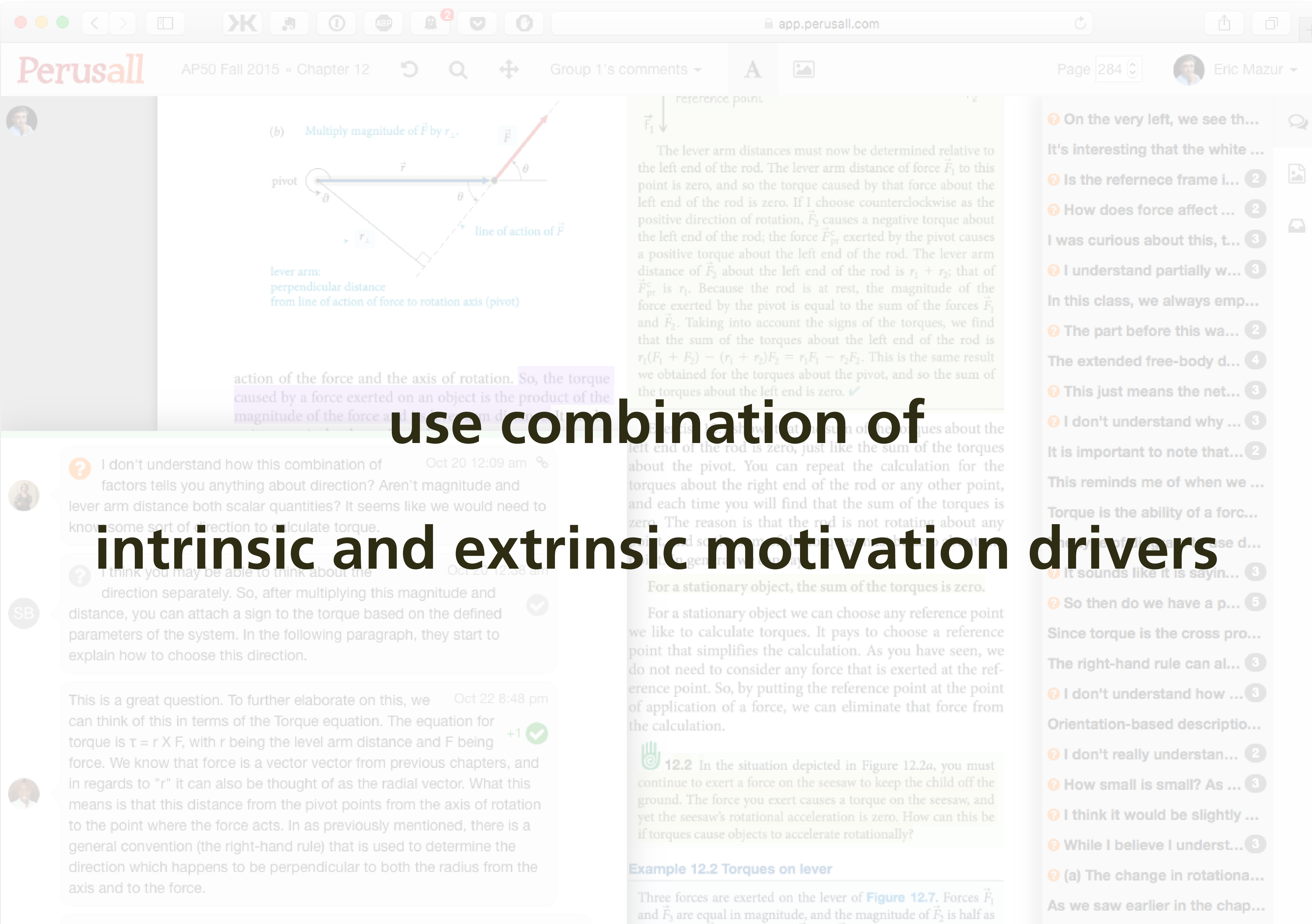
1 information transfer



1 information transfer



use combination of

intrinsic and extrinsic motivation drivers

1 design

2 approach

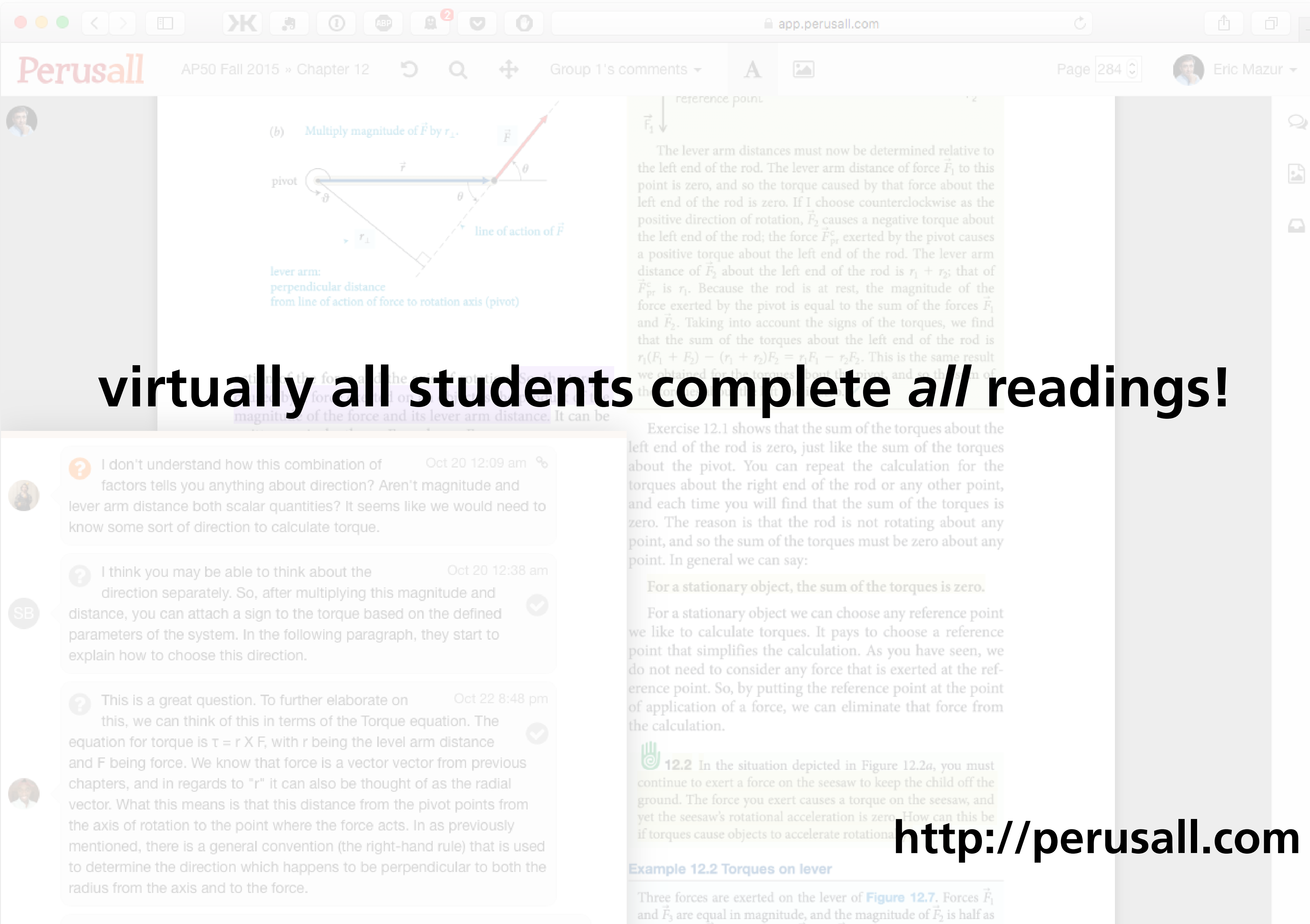
rubric-based assessment

- quality (thoughtfu… & i… …ret…on)
- que…ty (minimu… …o)
- timeliness (befo… cla…)
- di…ribu…o… (n…t c…st…

over 20,000 annotations!

1 design

2 approach



virtually all students complete *all* readings!

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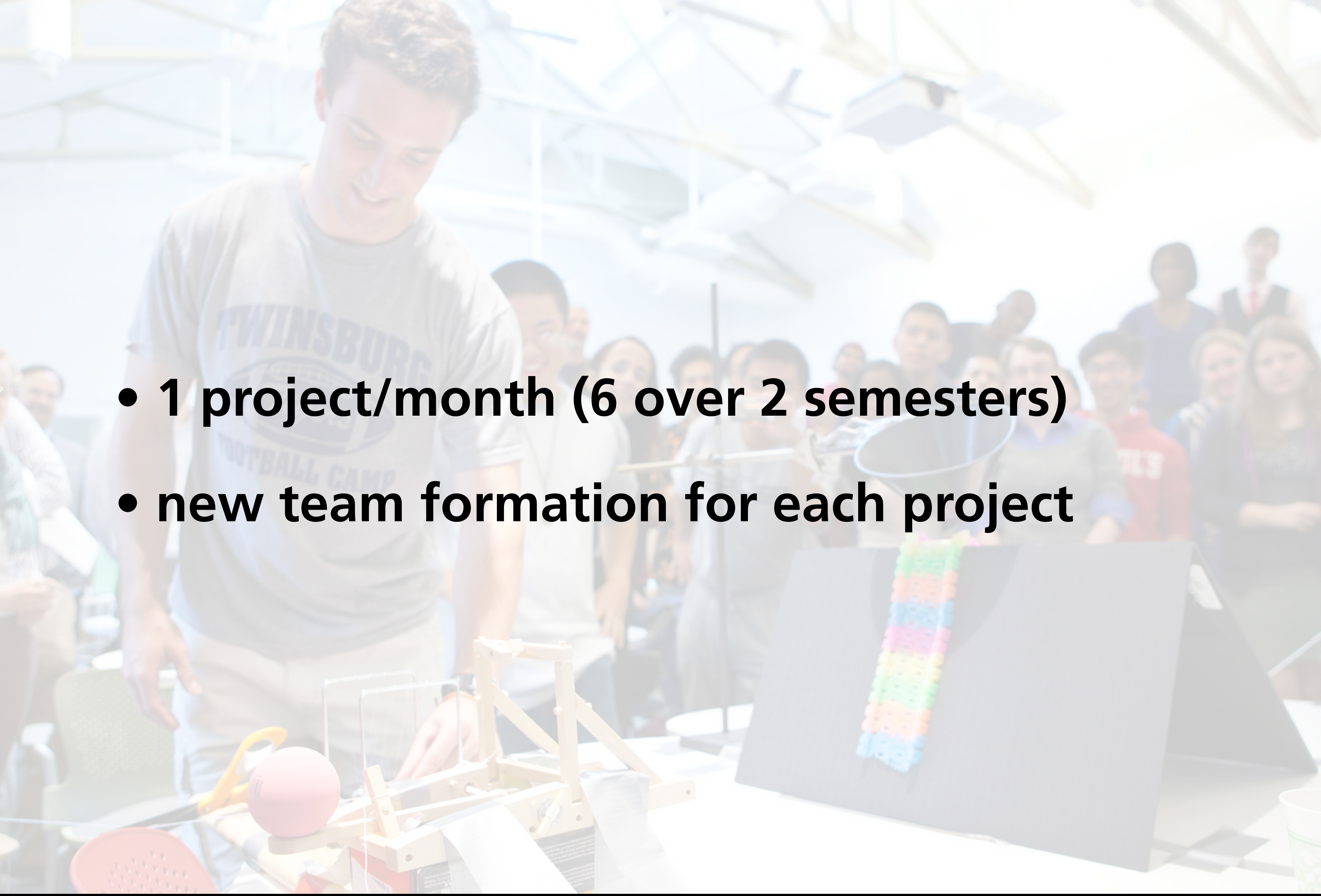
1 information transfer

1 information transfer 2 projects



- 1 project/month (6 over 2 semesters)
- new team formation for each project

1 information transfer **2** projects

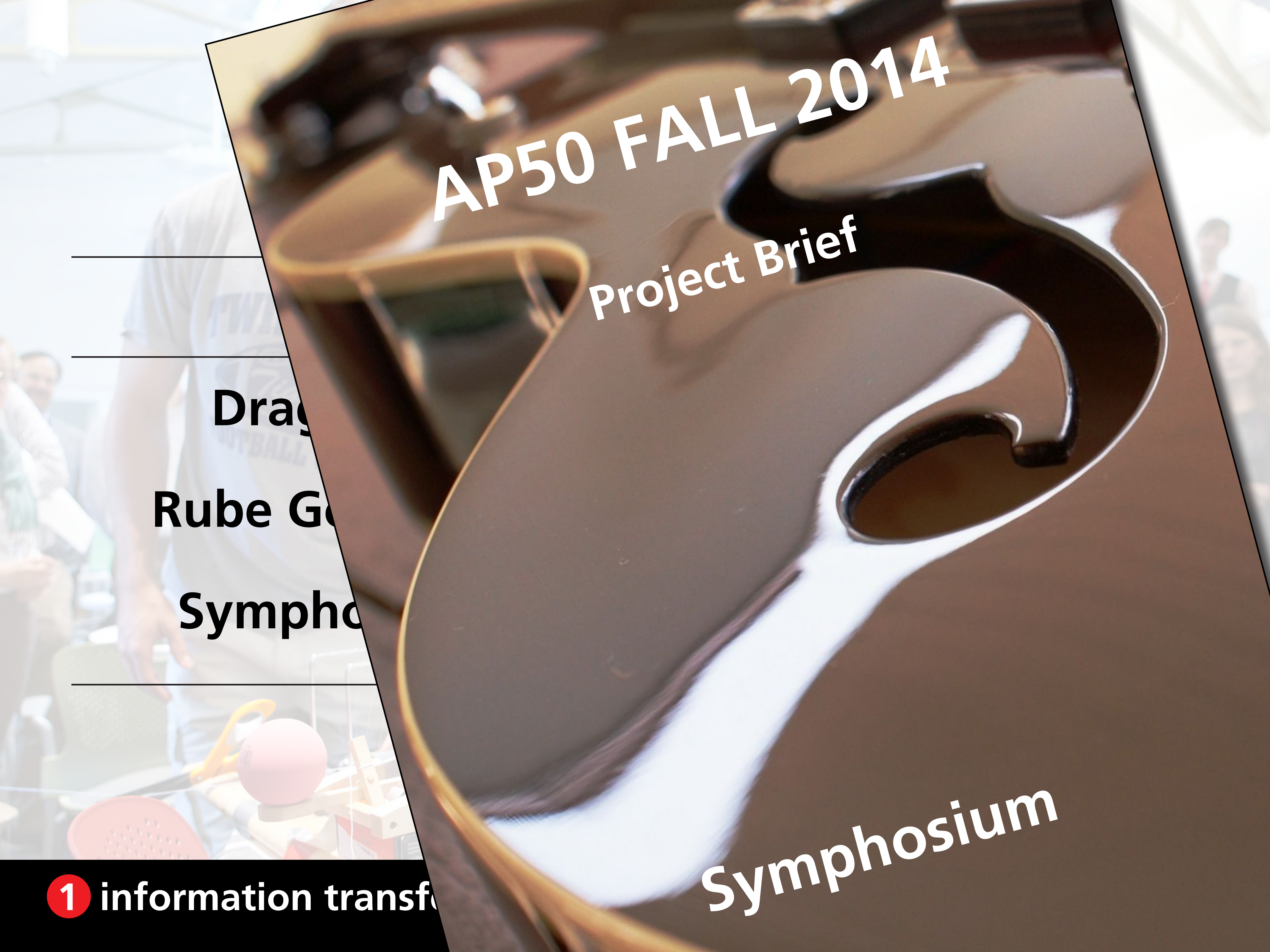
Projects

To be successful, the projects must

- require practical application of skills
- be linked to real world problems
- have compelling narrative (help/do good)

Projects

Fall	Spring
Drag Race	Ecotricity
Rube Goldberg	Crack-a-Thon
Symphosium	inSPECT Fair


AP50 FALL 2014
Project Brief
Symphosium

1 design

2 approach

Projects

Projects

Build a beautifully sounding instrument from recycled parts

Projects

Build a beautifully sounding instrument from recycled parts

- musical range
- *Q*-factor
- harmonic spectrum
- sound level
- tuning stability

Projects

Milestones:

- team contract
- proposal
- fair
- report
- team, peer, and self assessment

Projects

Milestones:

- team contract (at beginning)
- proposal
- fair
- report
- team, peer, and self assessment

Projects

Milestones:

- team contract (at beginning)
- proposal (+1 week)
- fair
- report
- team, peer, and self assessment

Projects

Milestones:

- team contract (at beginning)
- proposal (+1 week)
- fair (+3 weeks)
- report
- team, peer, and self assessment

Projects

Milestones:

- team contract (at beginning)
- proposal (+1 week)
- fair (+3 weeks)
- report (+1 week +3 days for revision)
- team, peer, and self assessment

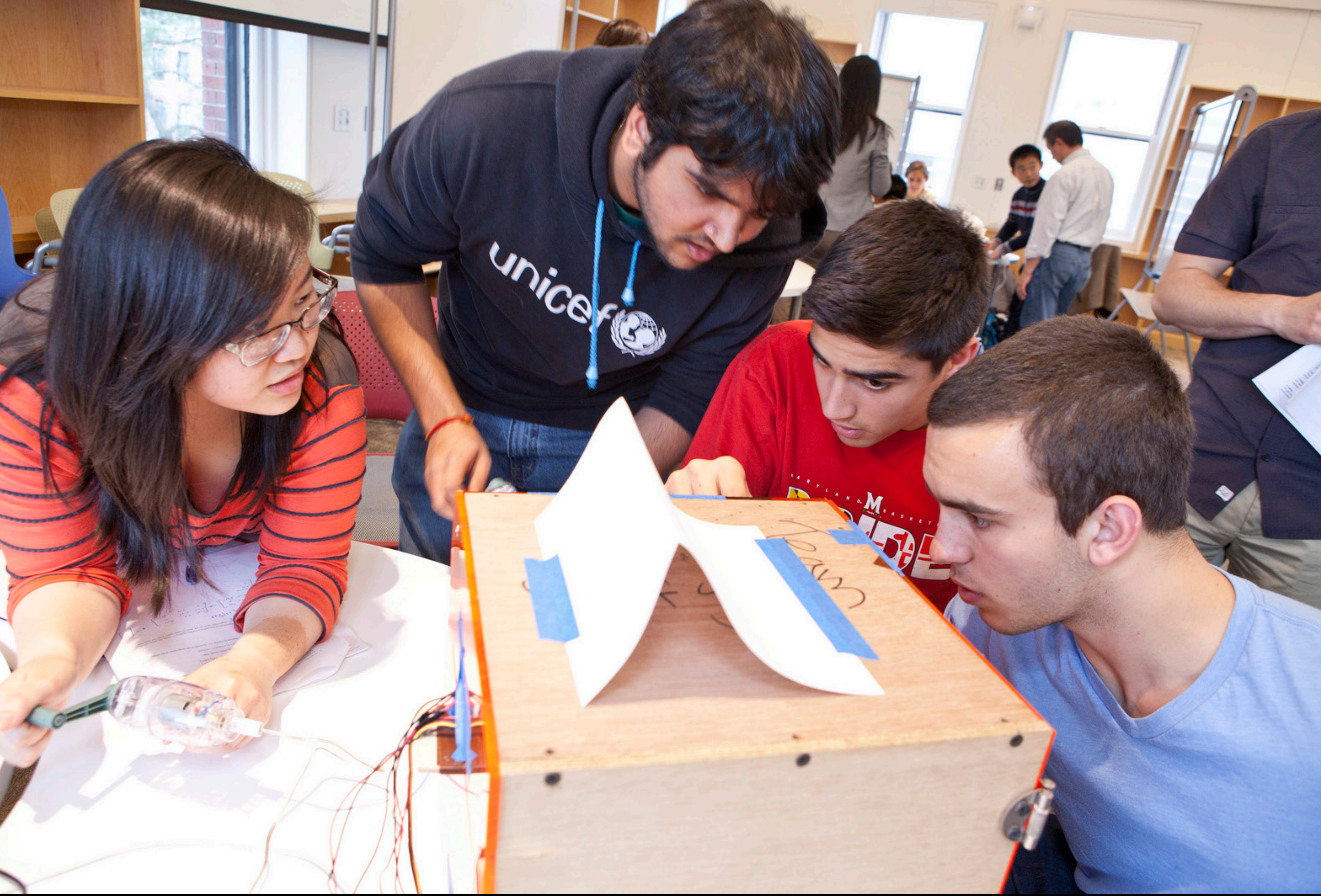
Projects

Milestones:

- team contract (at beginning)
- proposal (+1 week)
- fair (+3 weeks)
- report (+1 week +3 days for revision)
- team, peer, and self assessment (at end)

1 design

2 approach



1 information transfer

2 projects

competition instead of

social good/empathy as motivator

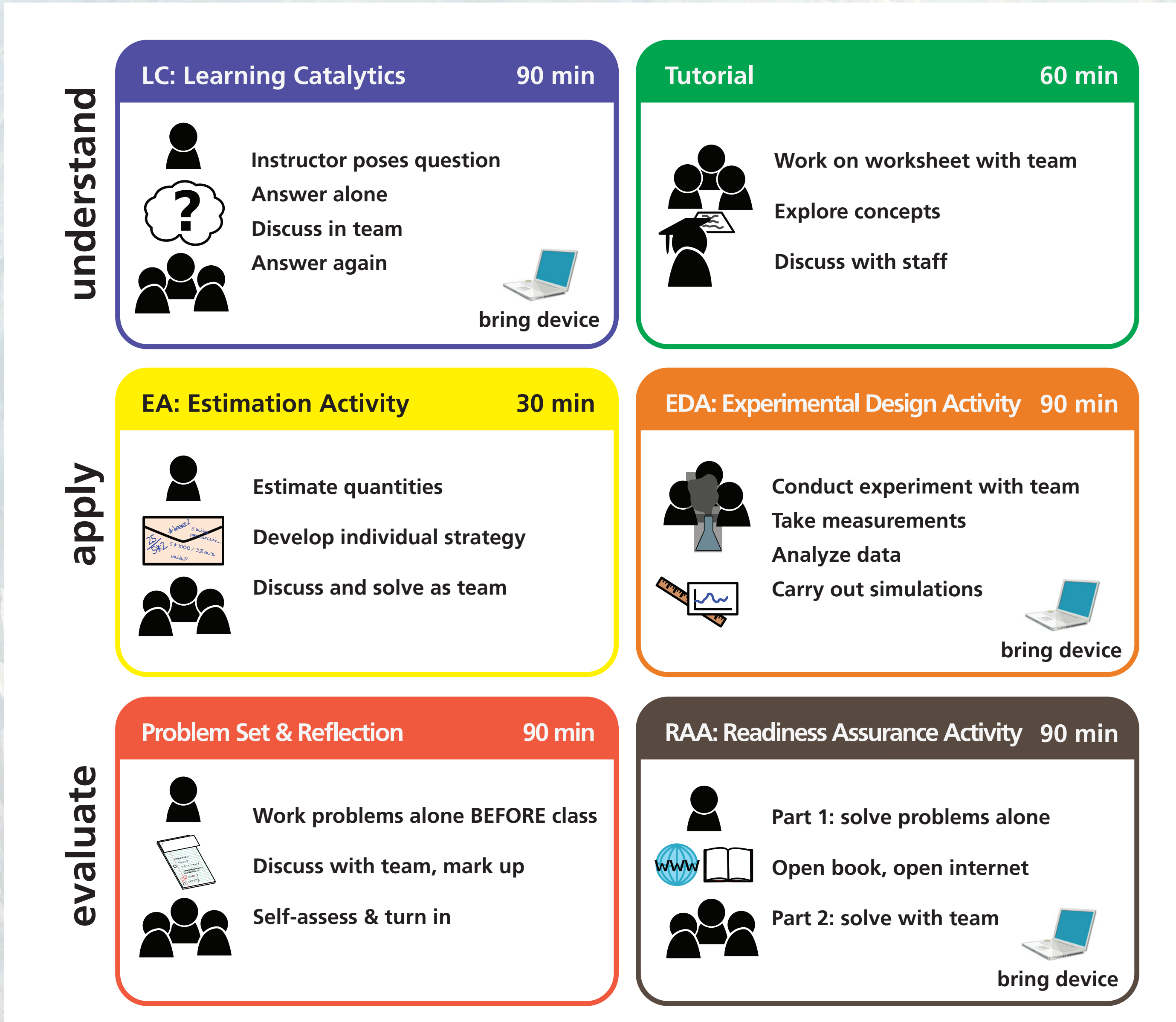
1 information transfer

2 projects

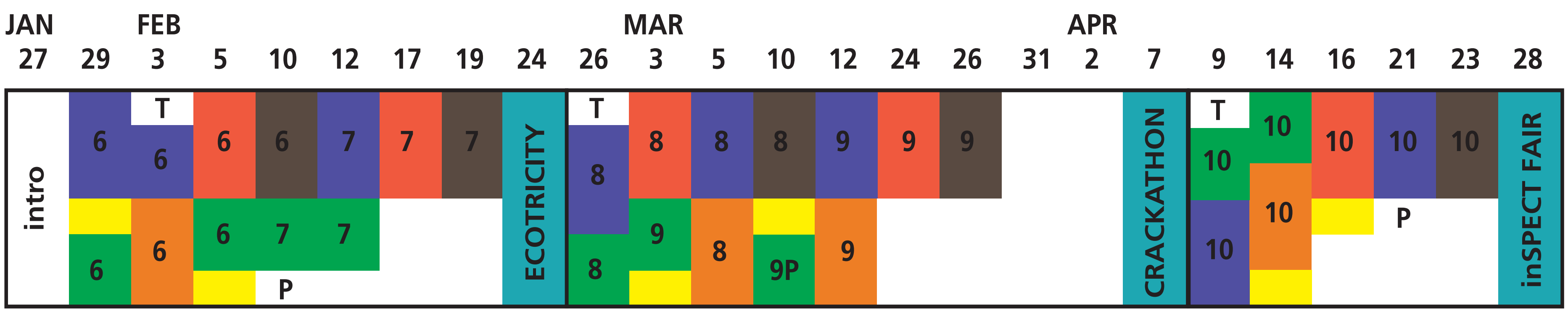
2 weekly 3-hour class periods

1 information transfer
2 projects
3 in-class activities

blend of 6 scaffolded “best practices”

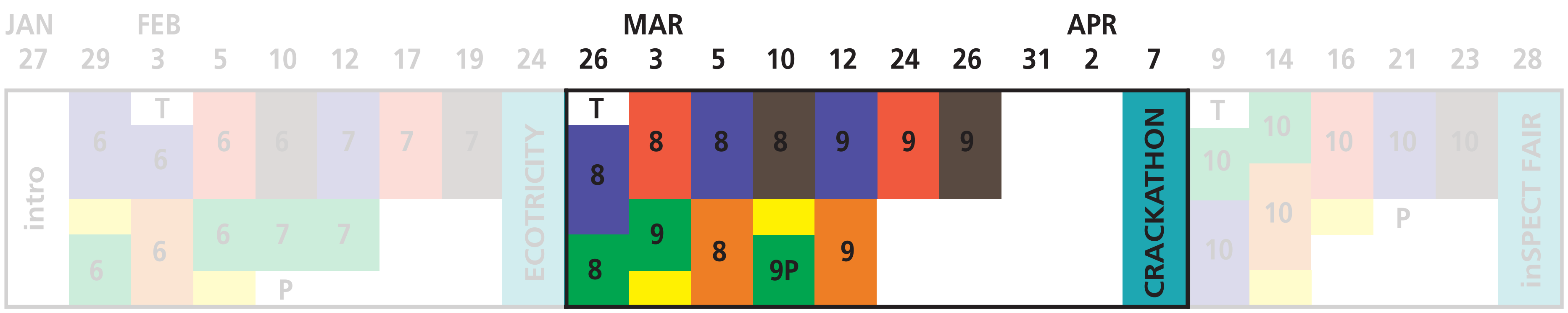


1 information transfer   2 projects   3 in-class activities



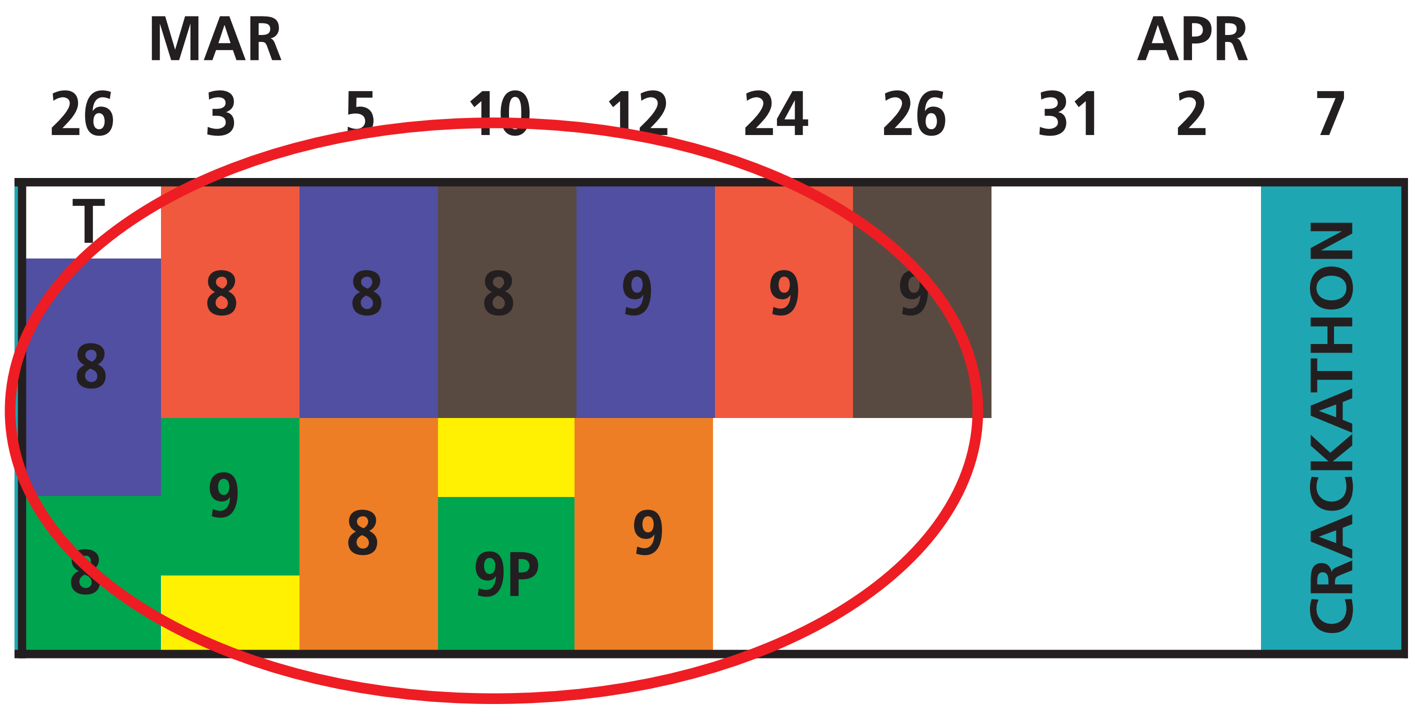
1 information transfer
2 projects
3 in-class activities

one project

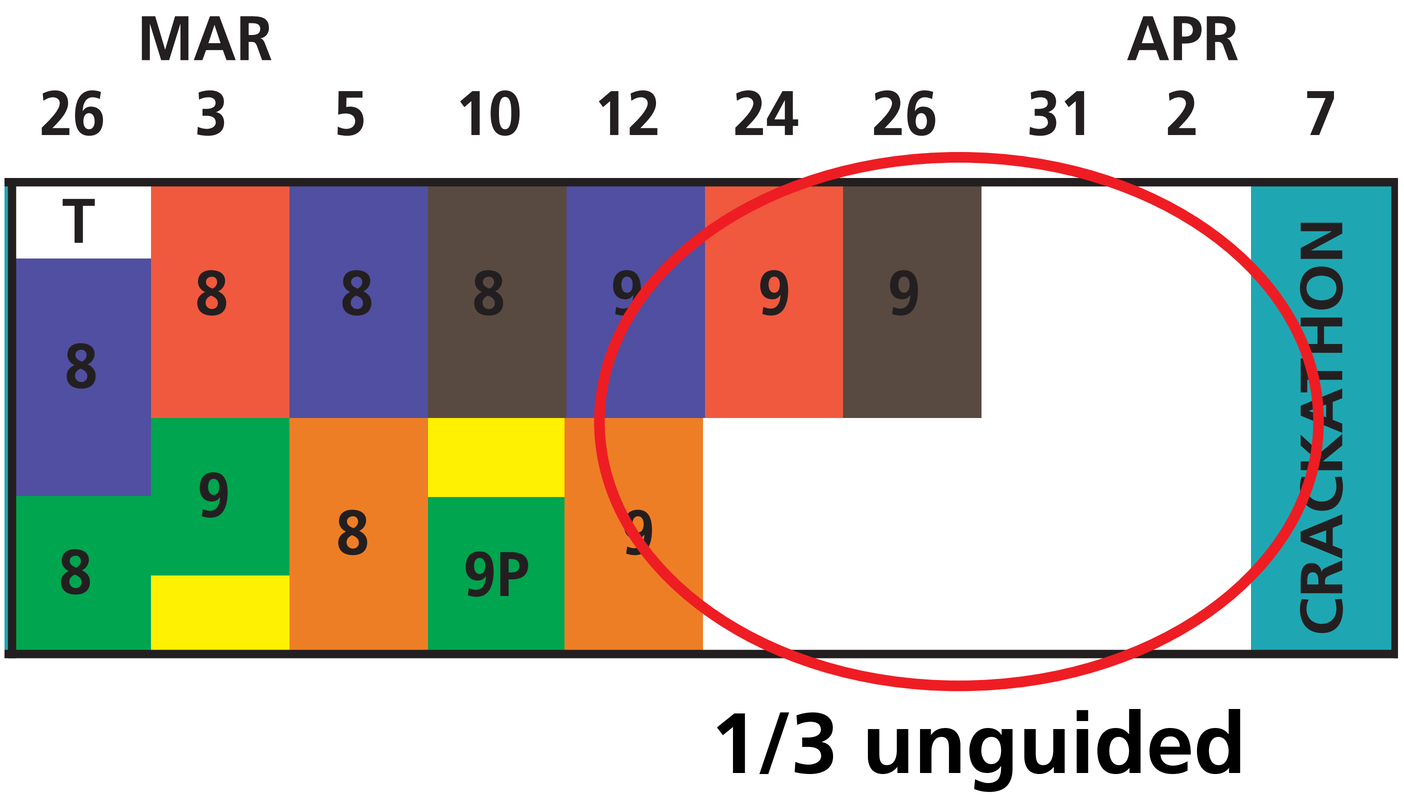


1 information transfer 2 projects 3 in-class activities

2/3 scaffolded, guided

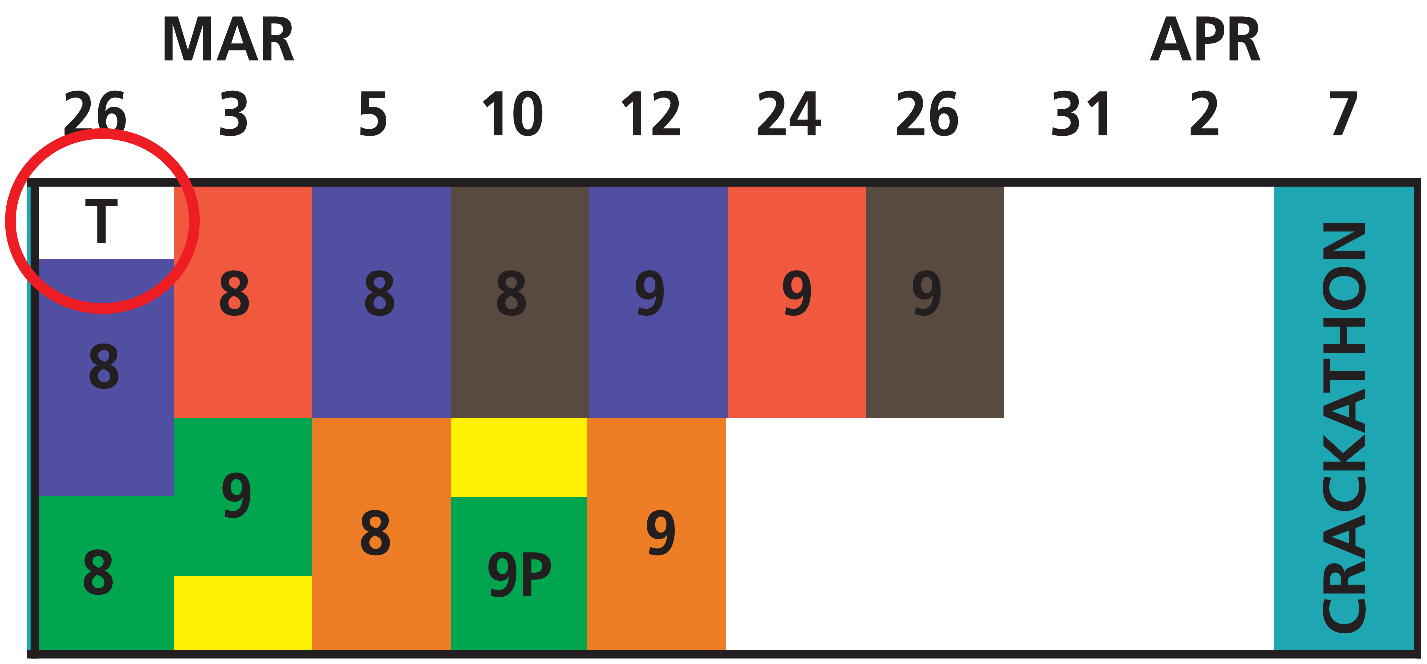


1 information transfer 2 projects 3 in-class activities

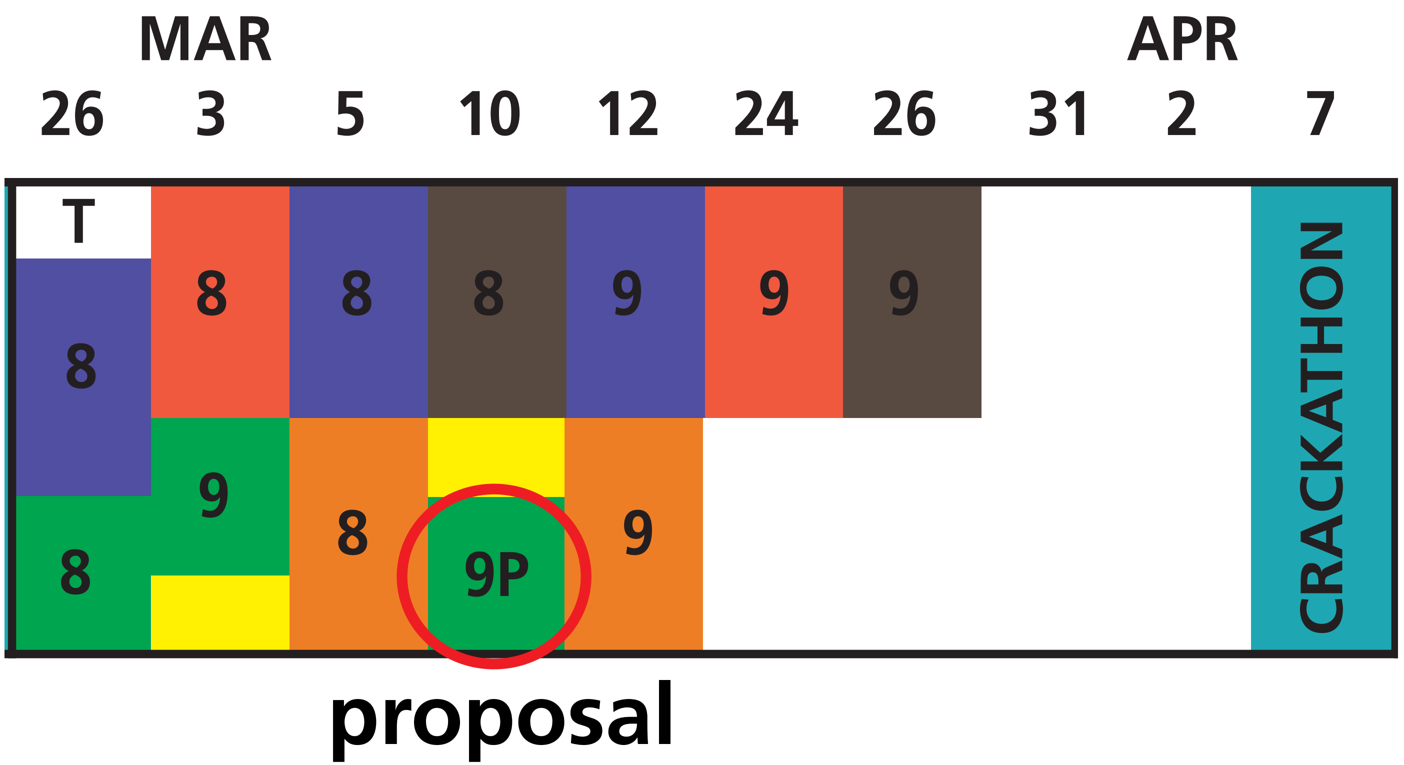


1 information transfer
2 projects
3 in-class activities

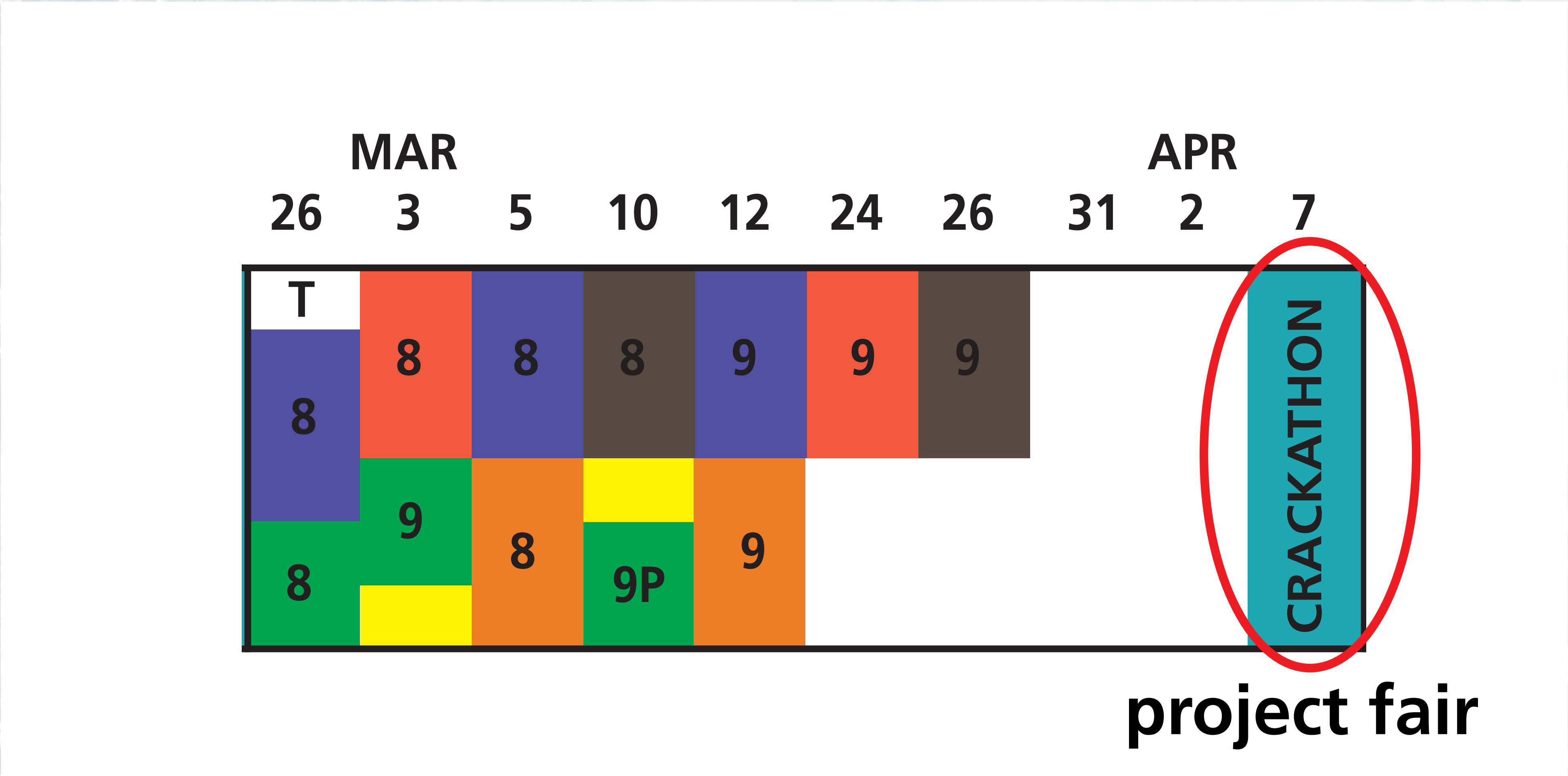
team intro



1 information transfer 2 projects 3 in-class activities



1 information transfer 2 projects 3 in-class activities



1 information transfer 2 projects 3 in-class activities

Assessment

- self-directed learning
- content learning goals
- teamwork
- professionalism

Ownership

Ownership

Course evaluation: 4.2/5

Ownership

“The structure of the class made what was my least-favorite subject into one of my favorites.

Ownership

"The structure of the class made what was my least-favorite subject into one of my favorites. I was worried that people, including myself, would just slack off and do the bare minimum, but you really need to be on top of your readings and concepts in order to contribute to your team. GREAT CLASS!!!!!!"

Ownership

"Dear Harvard students, this class will be unlike any class you've taken at Harvard, and it will, hopefully, shift the entire foundation upon which you've based your education. I truly believe everyone should take this course; prepare to take full ownership of your learning."

Ownership

Attendance: 94% (AP50a), 97% (AP50b)

Ownership

Attendance: 94% (AP50a), 97% (AP50b)

3 hours and they don't *leave*!

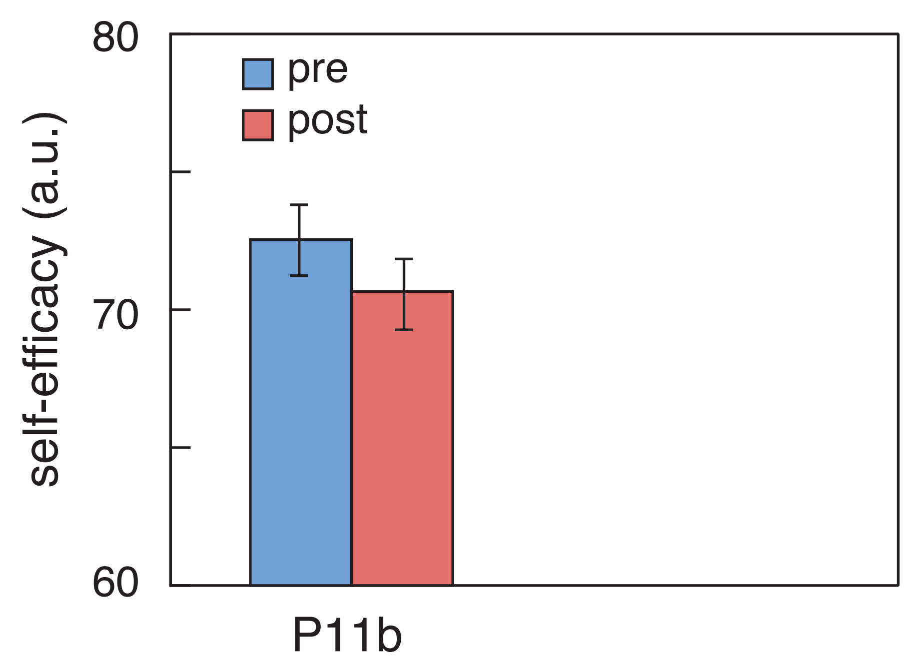
Ownership

"I don't think I am well enough to make it through class. I feel terrible because I don't want to let my team down by not being there, but I don't think I'd be very helpful in my current state."

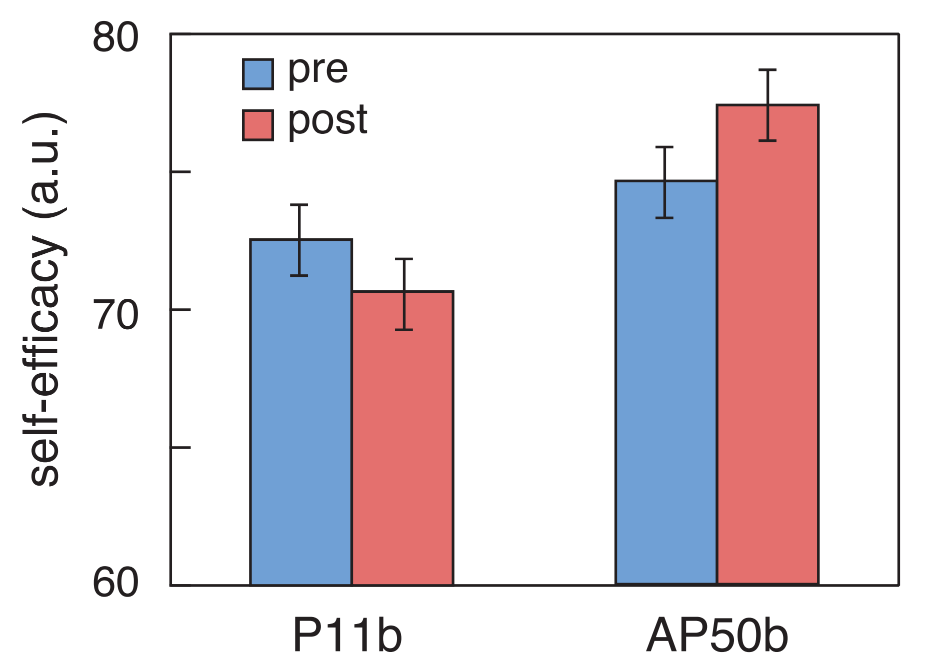
(via email)

Self-efficacy

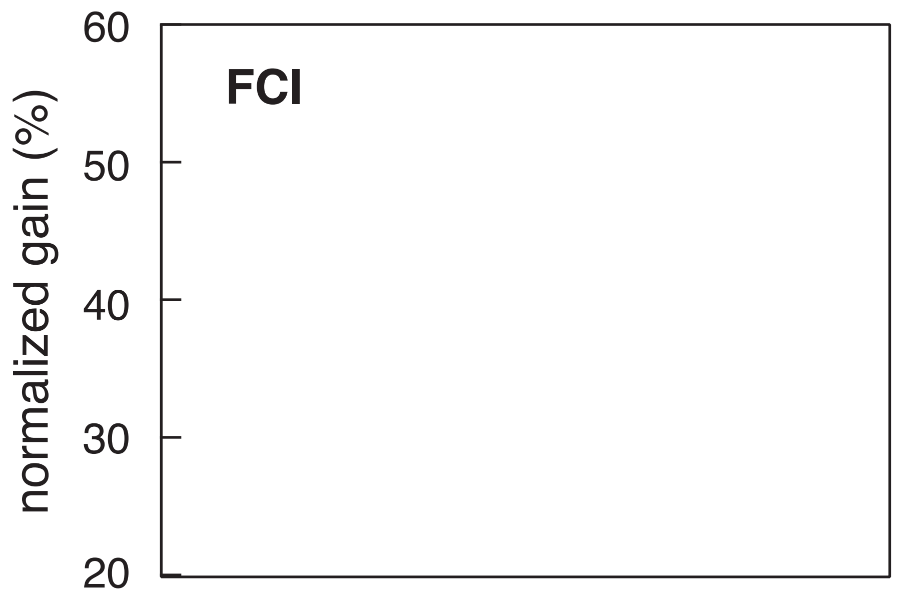
Self-efficacy



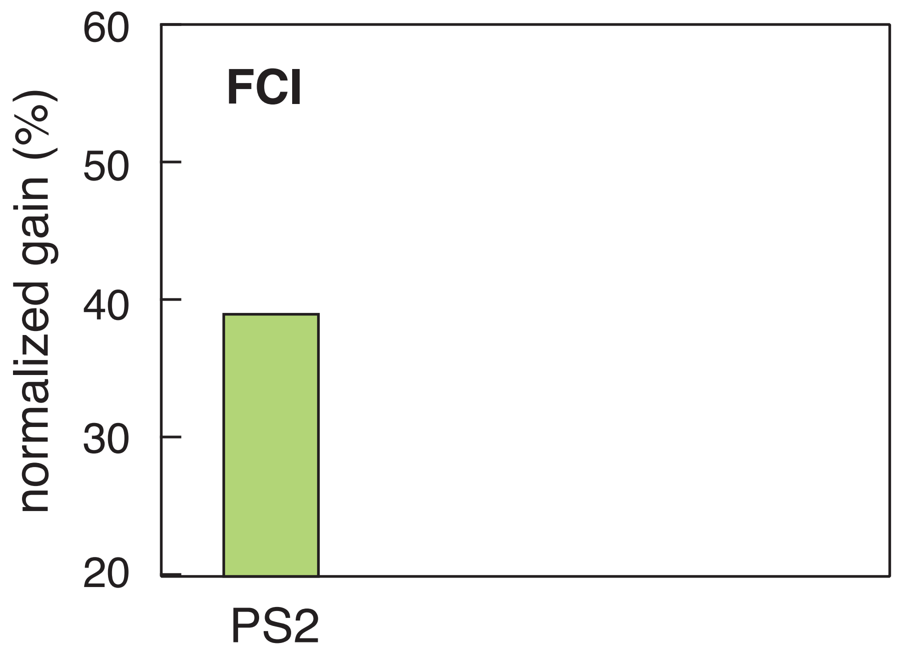
Self-efficacy



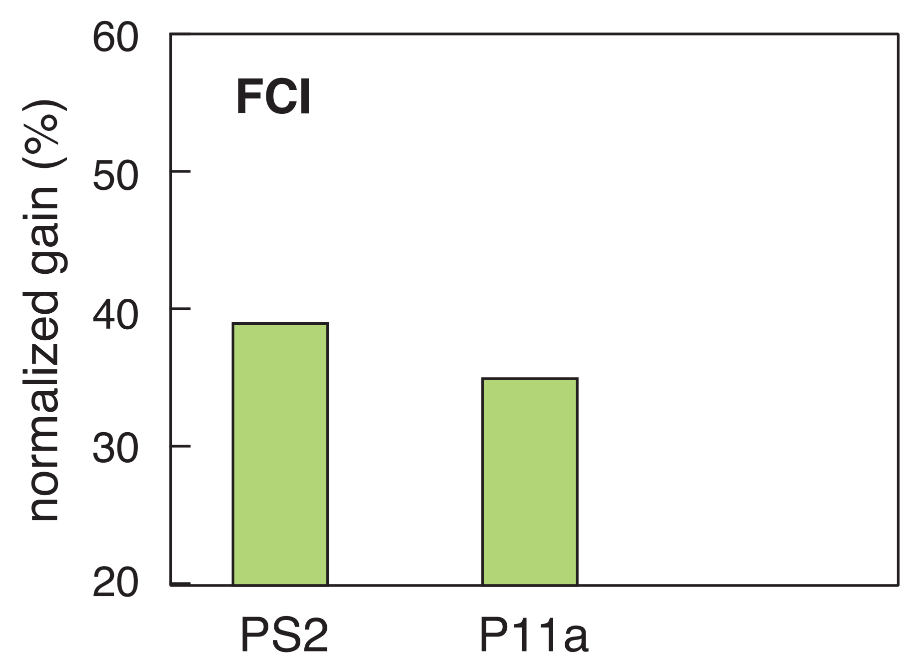
Conceptual Mastery



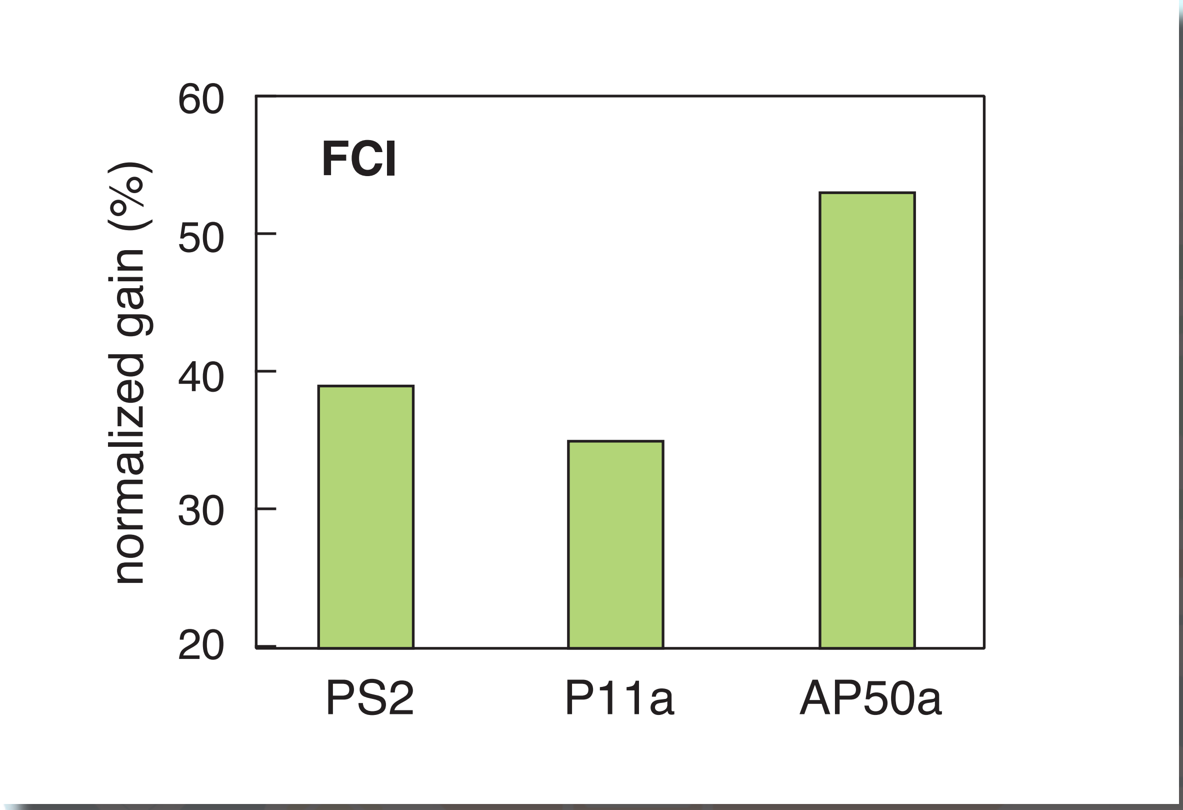
Conceptual Mastery



Conceptual Mastery



Conceptual Mastery



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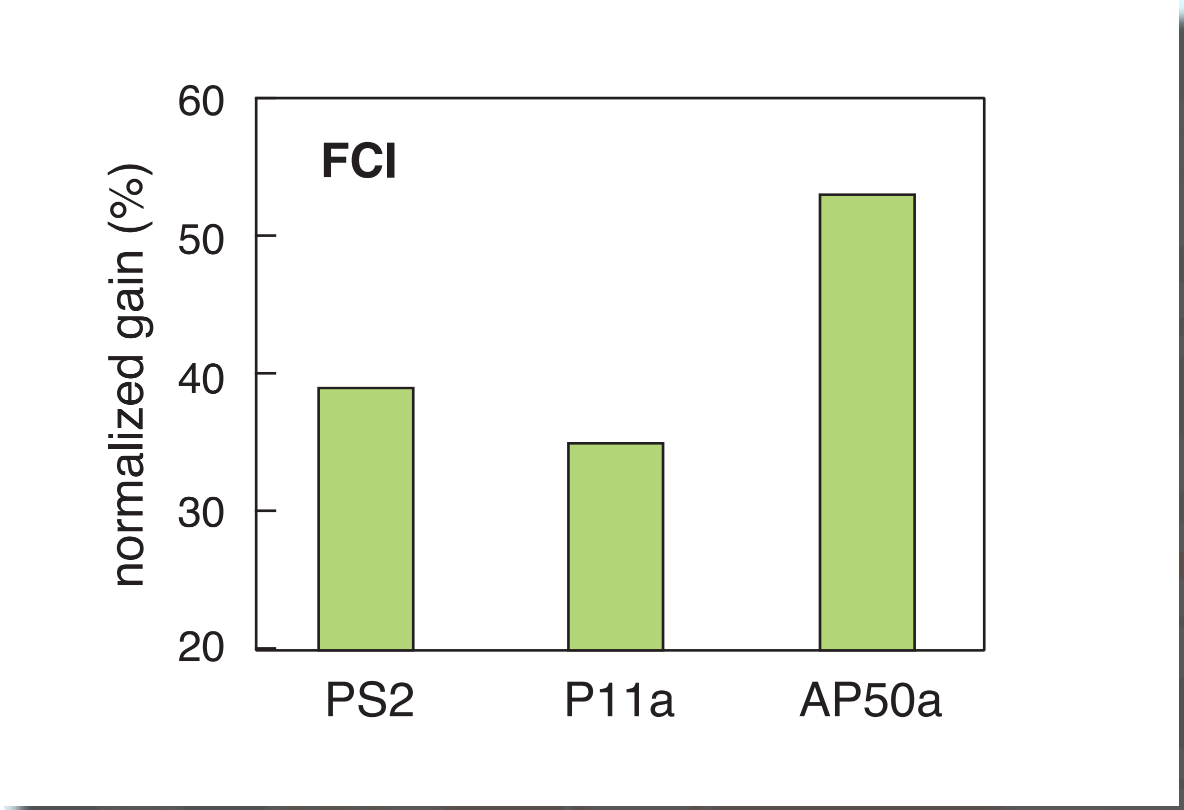
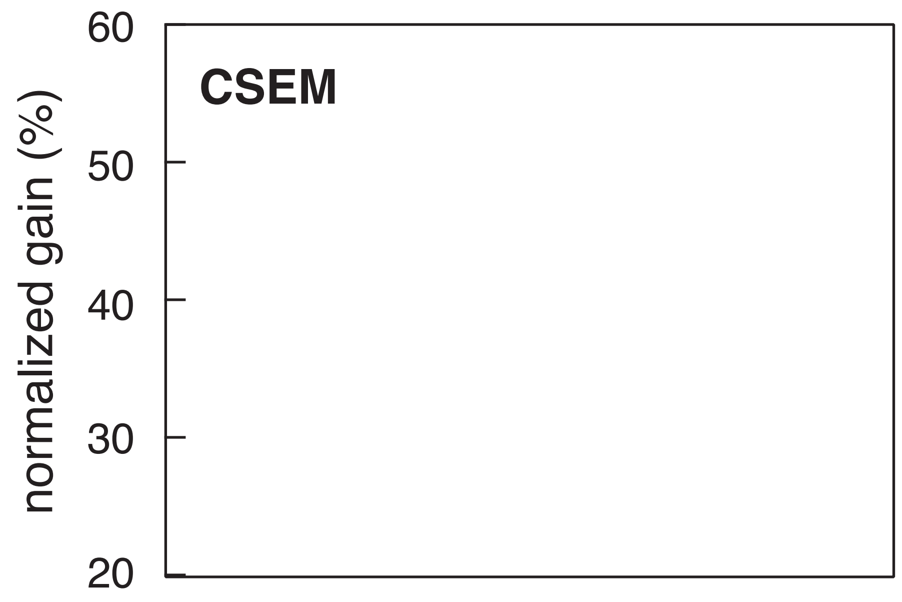
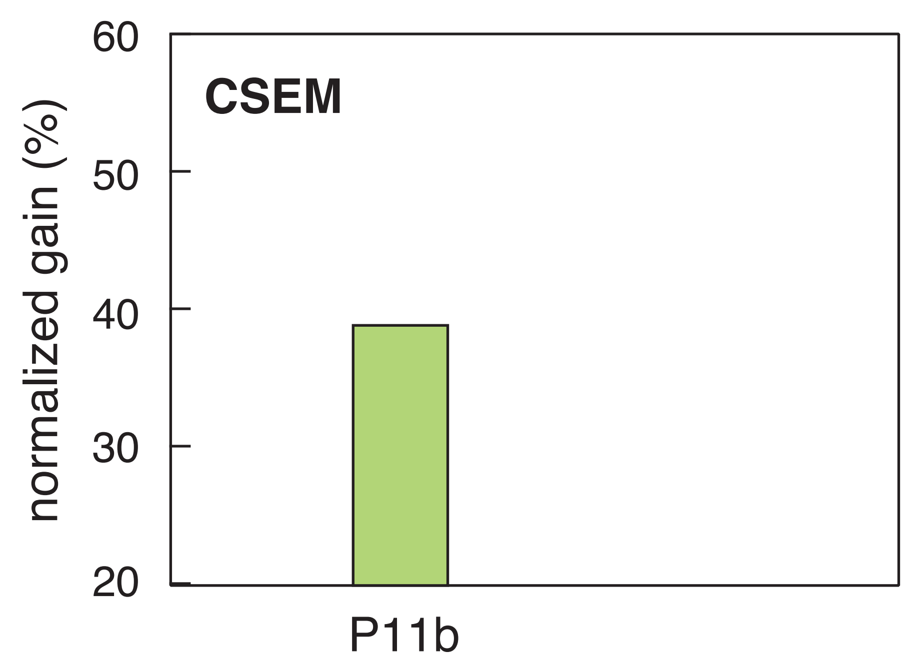


largest conceptual gain in *any* course past 6 yrs!

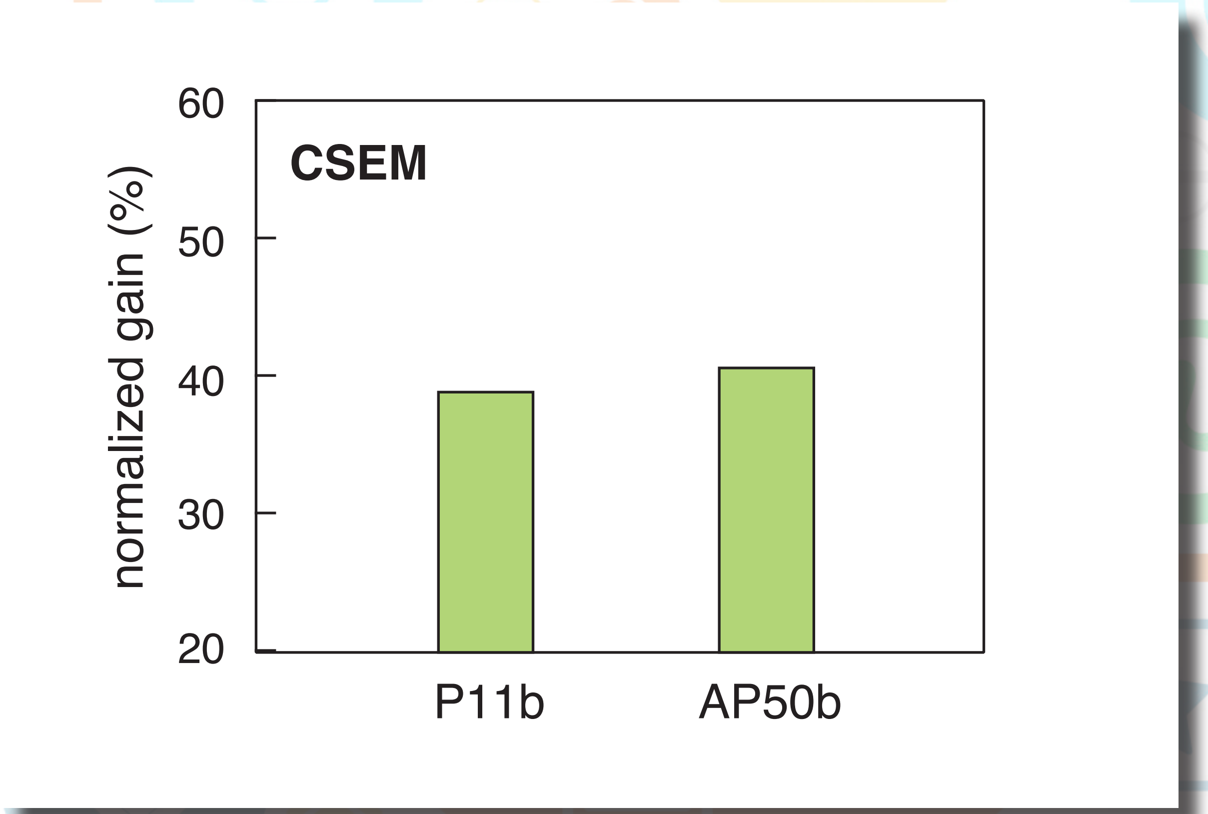
Conceptual Mastery



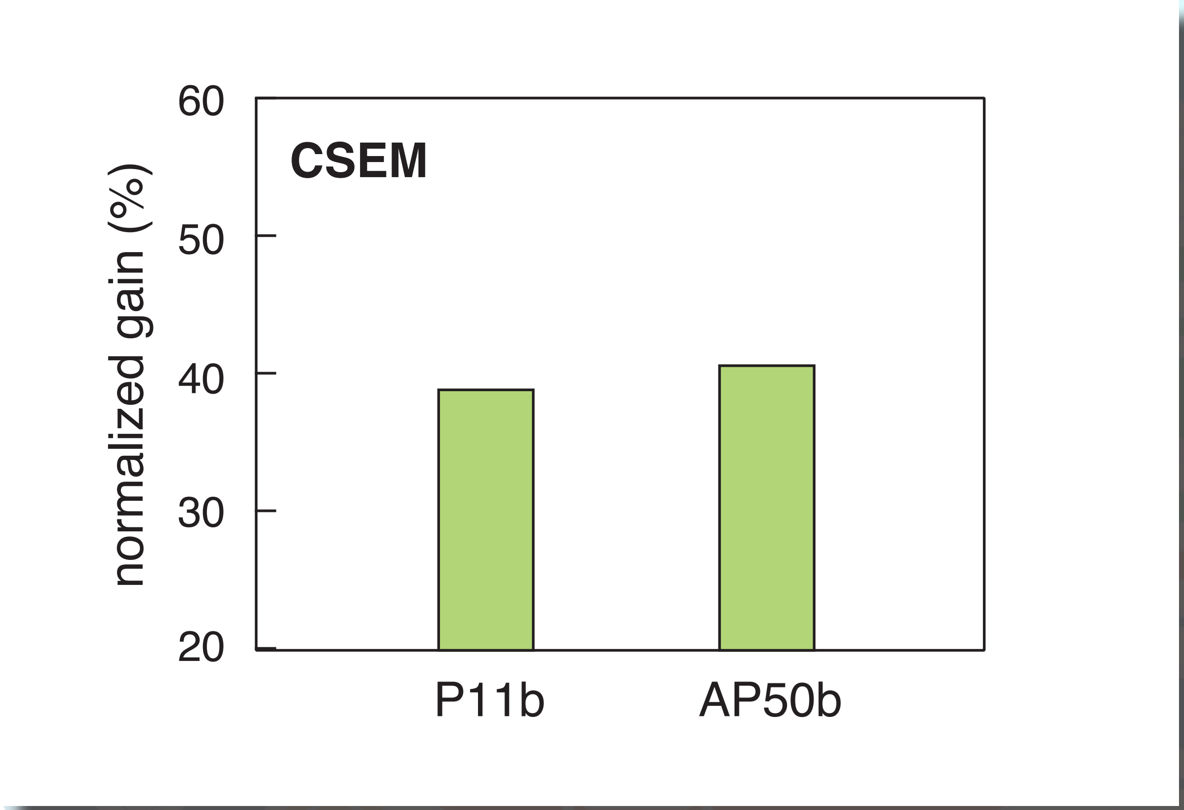
Conceptual Mastery



Conceptual Mastery



Conceptual Mastery



as good as when I do my best teaching!


Can create ownership of learning physics!


fun!
Can create ownership of learning physics!


”you come out with so much know-
ledge and experience and fun”

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