

Confessions of a converted lecturer



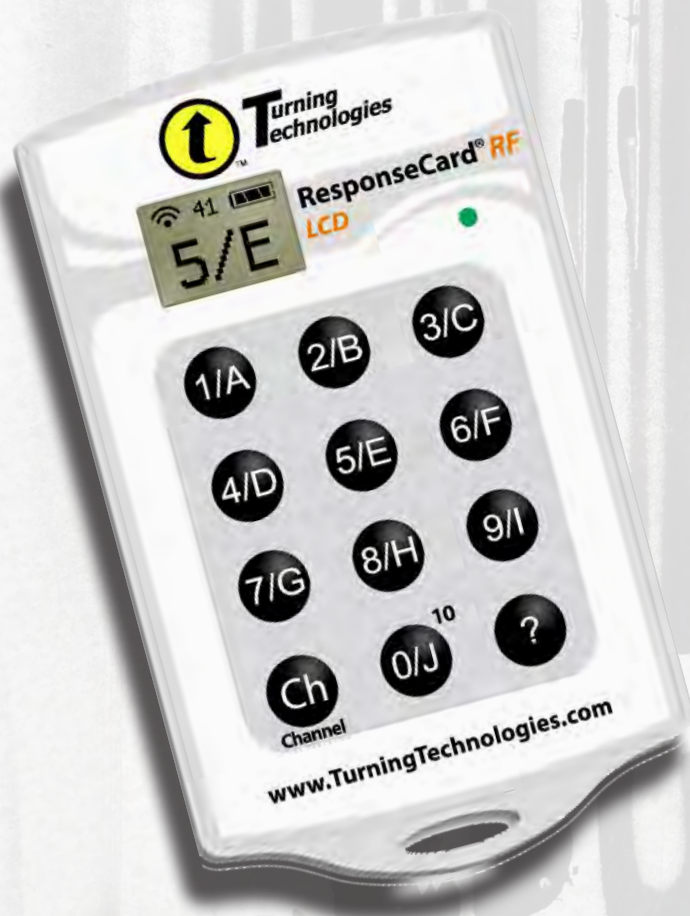
Colorado State University Pueblo
Pueblo, CO, 2 May 2016



Confessions of a converted lecturer



Colorado State University Pueblo
Pueblo, CO, 2 May 2016



- no ON/OFF button
- only last “click” counts
- display shows recorded answer



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unique ID on back of clicker

Think of something you are good at

EDUCACION

Think of something you are good at

How did you become good at this?

Became good at it by:

- 1. trial and error**
- 2. lectures**
- 3. practicing**
- 4. apprenticeship**
- 5. other**











1 education

2 PI


3 test



1 education

2 PI

3 test

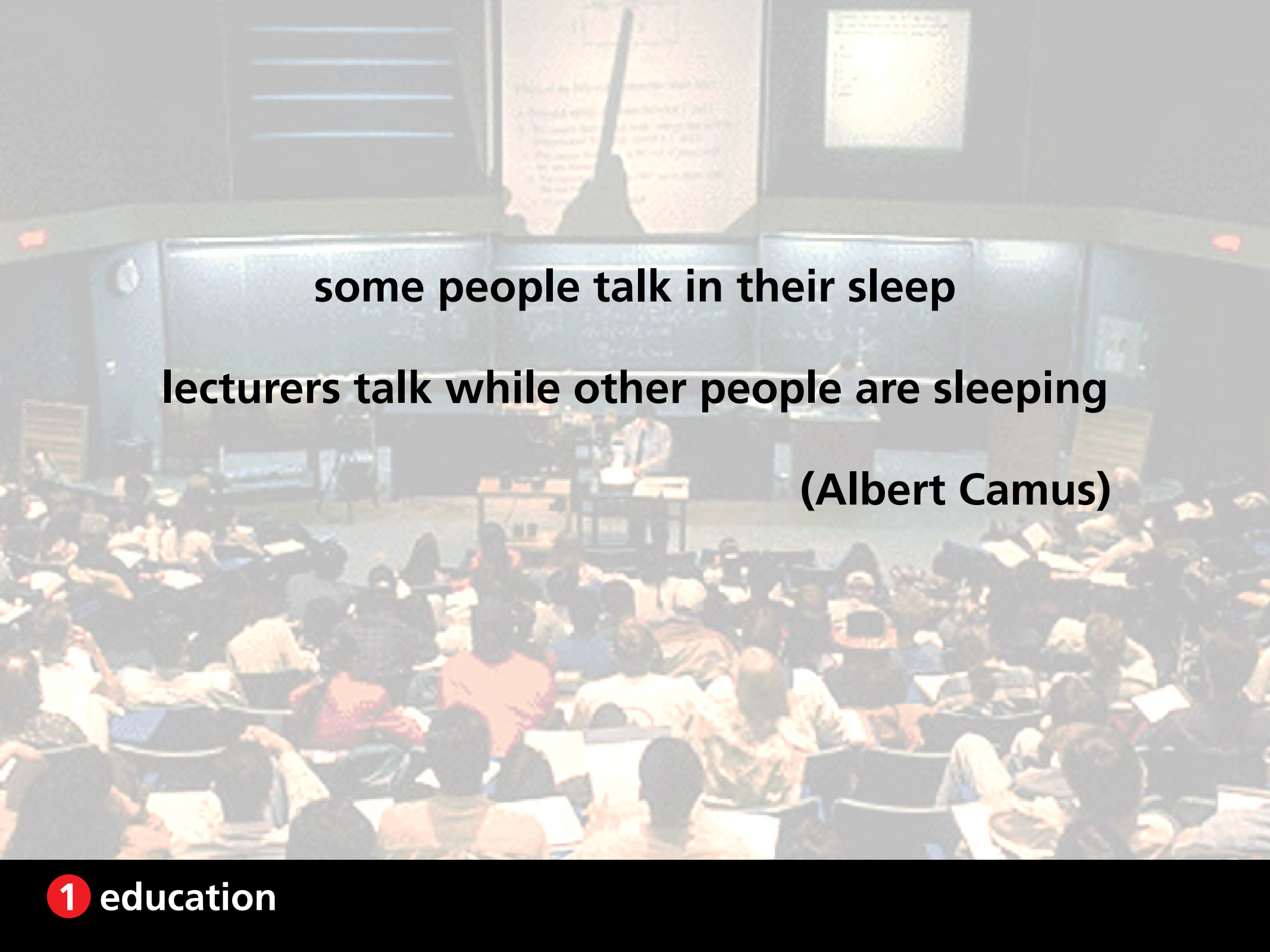


**What happens
in a lecture?**



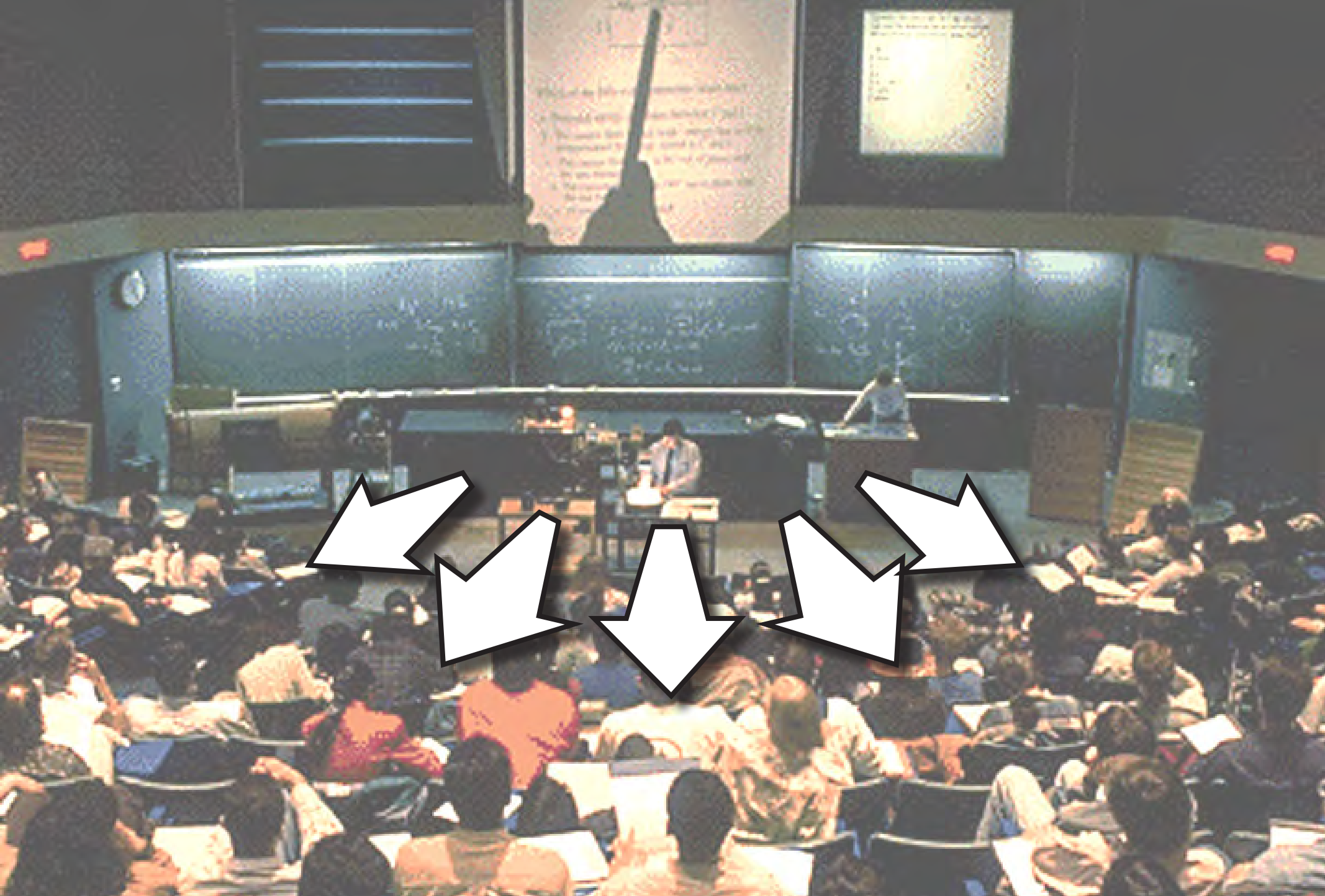
A wide-angle photograph of a large lecture hall. In the foreground, the backs of many students' heads are visible as they sit in rows of chairs, facing the front of the room. Some students have papers or laptops open. At the front of the hall, a lecturer stands behind a podium, addressing the class. Behind the lecturer is a large, curved wall featuring several blackboards with faint writing and a large projection screen displaying a presentation slide. The room is well-lit, and the overall atmosphere is that of a formal academic setting.

some people talk in their sleep

A large lecture hall filled with students. Many students are sleeping in their seats, with their heads resting on their desks or hands. The room has a curved front wall with a large screen and a lecturer standing at a podium. The text is overlaid on the image.

some people talk in their sleep
lecturers talk while other people are sleeping
(Albert Camus)





The result?

EDUCACION

Lack of learning

EDUCACION

Lack of learning

Lack of retention

not transfer but assimilation of information is key





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)

question

1 education

2 PI

question



think

question



think



poll

question



think



poll



discuss

question



think



poll



discuss



repoll

question



think



poll



discuss



repoll



explain





1 education

2 PI

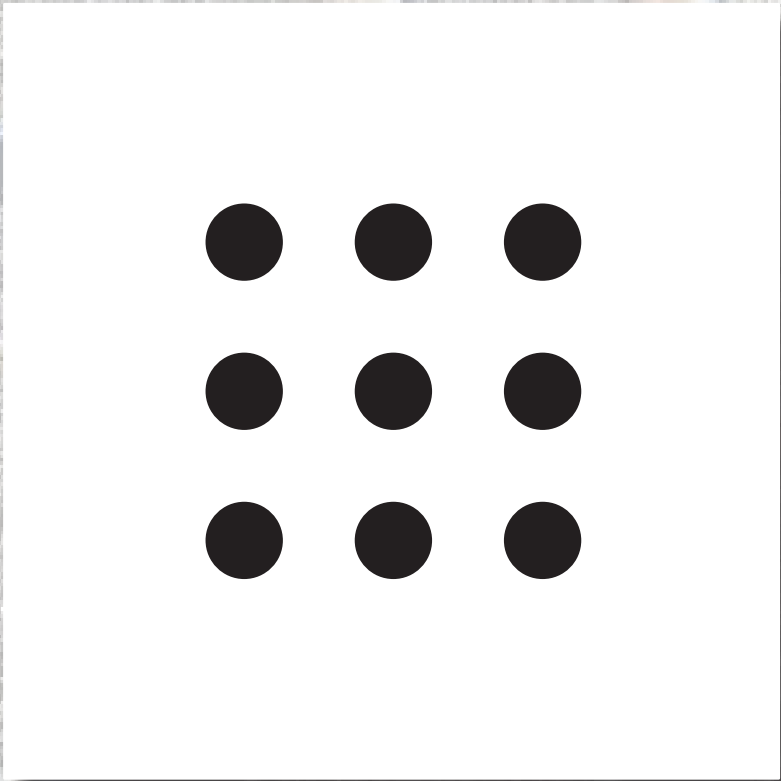


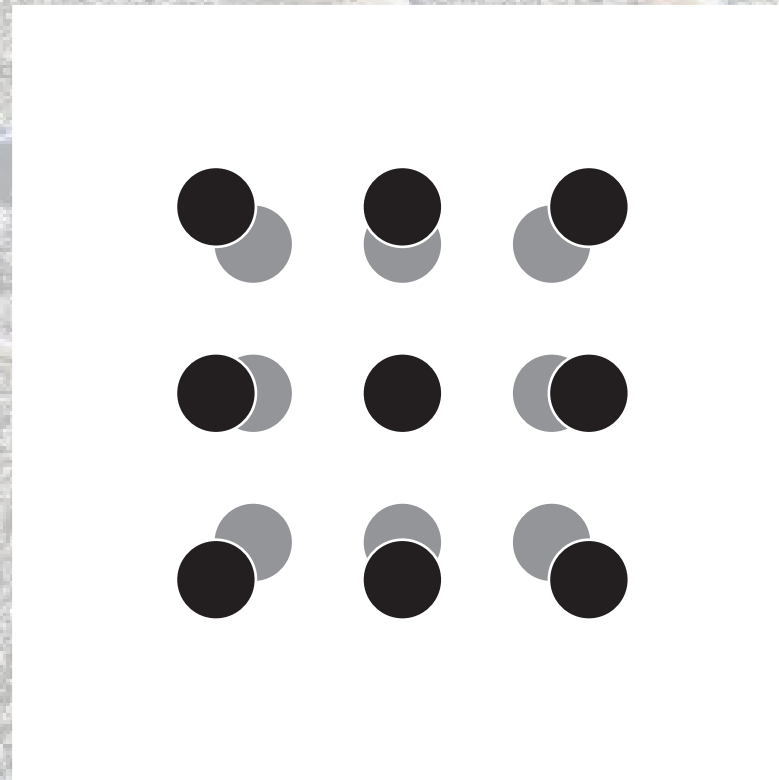
1 education

2 PI

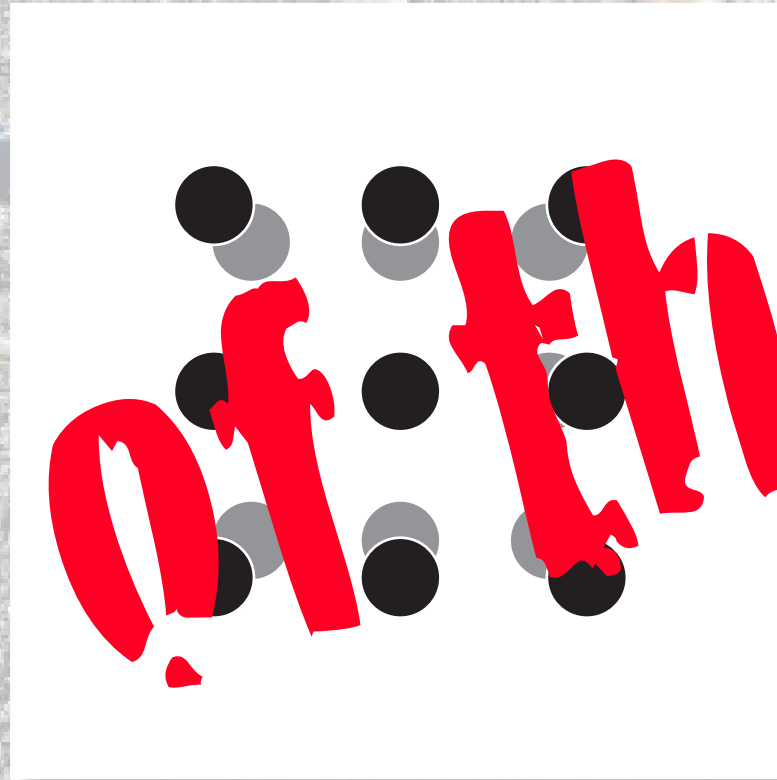


thermal expansion





all of them



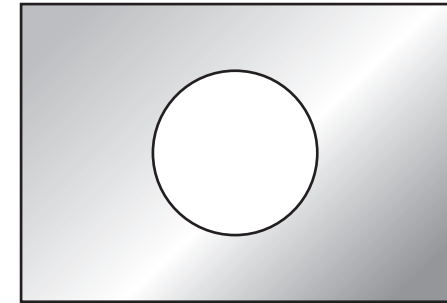
1 education

2 PI

**Consider a rectangular metal plate
with a circular hole in it.**



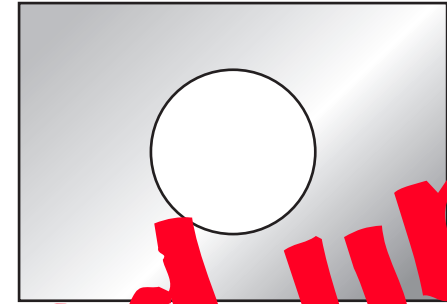
Consider a rectangular metal plate with a circular hole in it.



When the plate is uniformly heated, the diameter of the hole

- 1. increases.**
- 2. stays the same.**
- 3. decreases.**

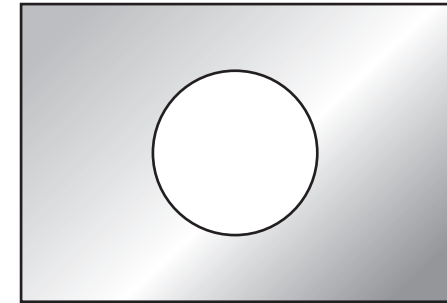
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- 2. stays the same.**
- 3. decreases.**

Before I tell you the answer...

Before I tell you the answer, let's analyze what happened.

Before I tell you the answer, let's analyze what happened.

You...

Before I tell you the answer, let's analyze what happened.

You...

1. made a commitment

Before I tell you the answer, let's analyze what happened.

You...

- 1. made a commitment**
- 2. externalized your answer**

Before I tell you the answer, let's analyze what happened.

You...

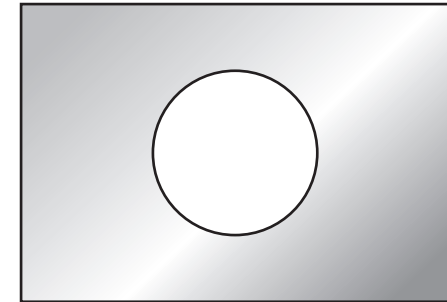
- 1. made a commitment**
- 2. externalized your answer**
- 3. moved from the answer/fact to reasoning**

Before I tell you the answer, let's analyze what happened.

You...

- 1. made a commitment**
- 2. externalized your answer**
- 3. moved from the answer/fact to reasoning**
- 4. became emotionally invested in the learning process**

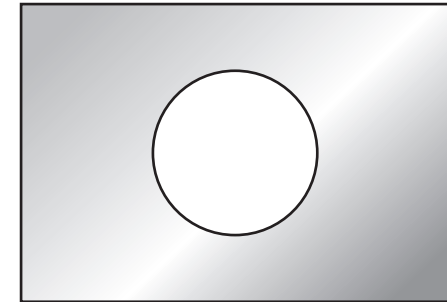
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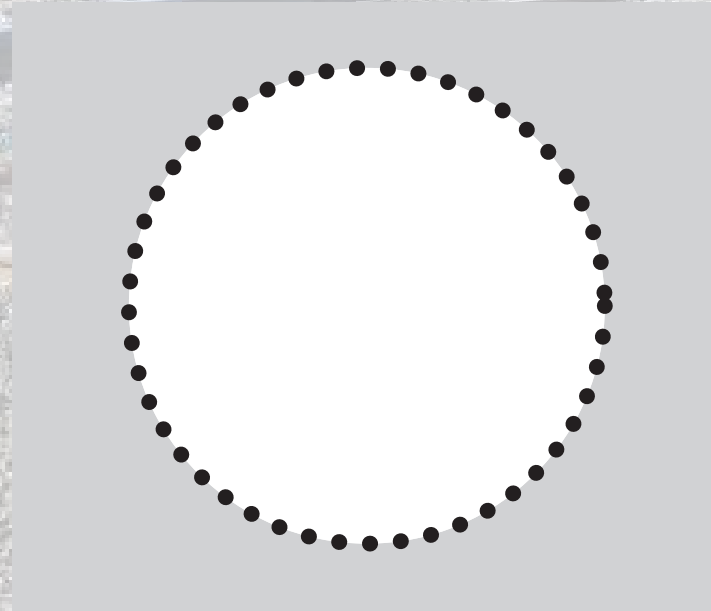
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When the plate is uniformly heated, the diameter of the hole

- 1. increases. ✓**
- 2. stays the same.
- 3. decreases.

consider atoms at rim of hole

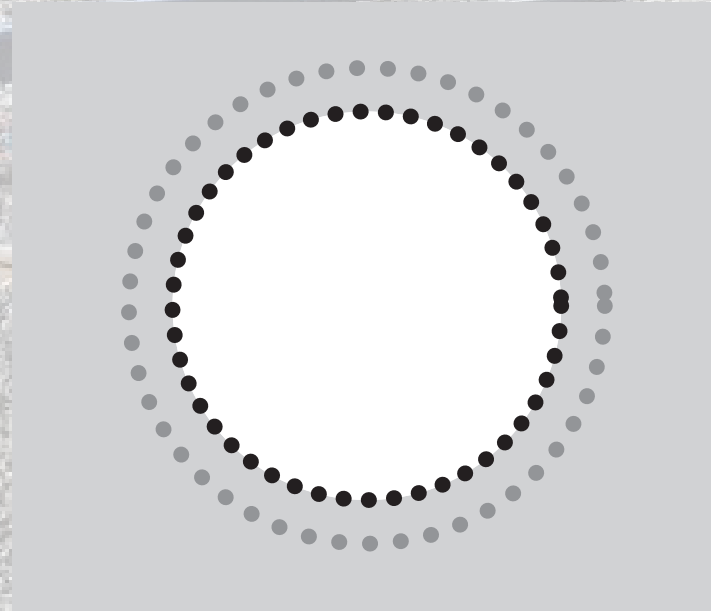


1 education

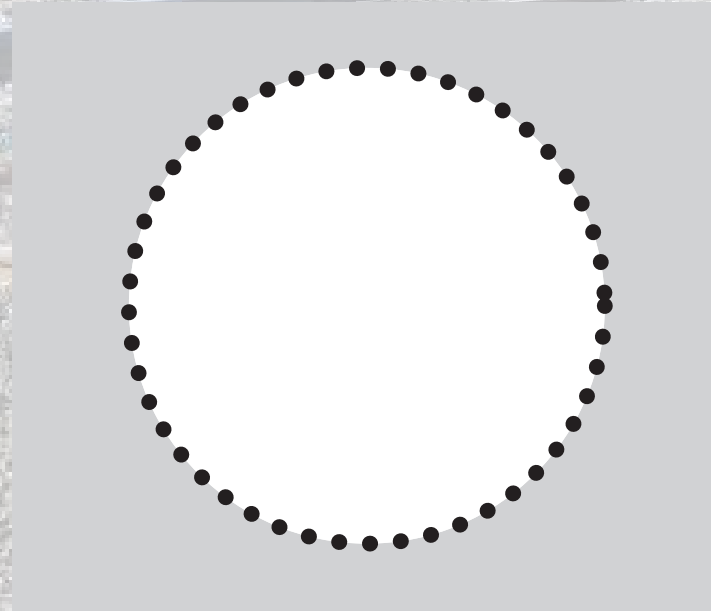
2 PI

3 test

consider atoms at rim of hole



consider atoms at rim of hole

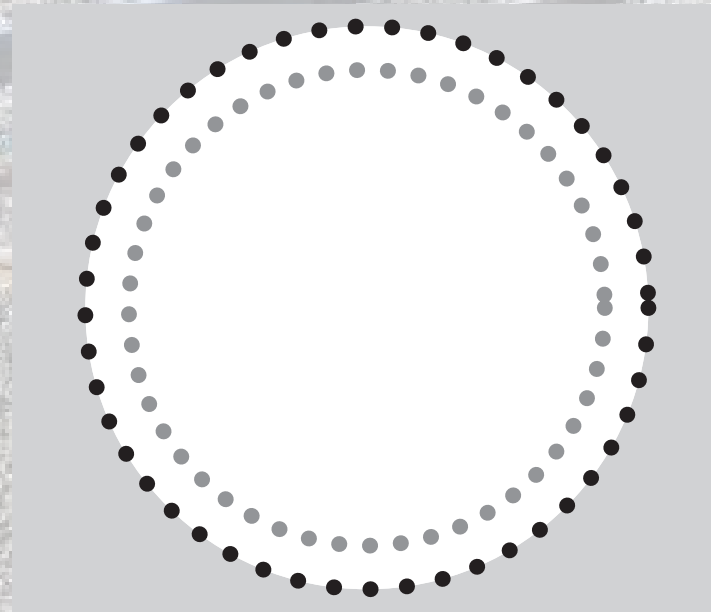


1 education

2 PI

3 test

consider atoms at rim of hole



consider atoms at rim of hole

you won't forget this

1 education

2 PI

3 test



Peer

back to PI

INSTRUCTION

1 education

2 PI

3 test

Peer
Greater learning gains



INSTRUCTION

1 education

2 PI

3 test



Peer

Greater learning gains

Better retention

INSTRUCTION

1 education

2 PI

3 test



1 education

2 PI

3 test

in a lecture, students...

1 education

2 PI

3 test

in a lecture, students...

1. don't pay utmost attention

in a lecture, students...

1. don't pay utmost attention

2. think they know it

in a lecture, students...

- 1. don't pay utmost attention**
- 2. think they know it**
- 3. are not confronted with misconceptions**

in a lecture, students...

1. don't pay utmost attention

2. think they know it

3. are not confronted with misconceptions

false
sense of security



1 education

2 PI

3 test

The background is a faded, classical-style painting. It depicts a face, possibly a classical figure, with multiple eyes visible. The eyes are arranged vertically, with one eye at the top, a central eye, and another at the bottom. The face is rendered in a pale, yellowish-tan color, and the eyes are a light blue or grey. The overall style is reminiscent of a classical portrait, possibly a fresco or a painting on a wall. The text "an illusion. . ." is overlaid in a bold, red, serif font, centered horizontally and slightly below the middle vertically.

an illusion. . .

1 education

2 PI

3 test



Education is not just about:

- **transferring information**
- **getting students to do what we do**

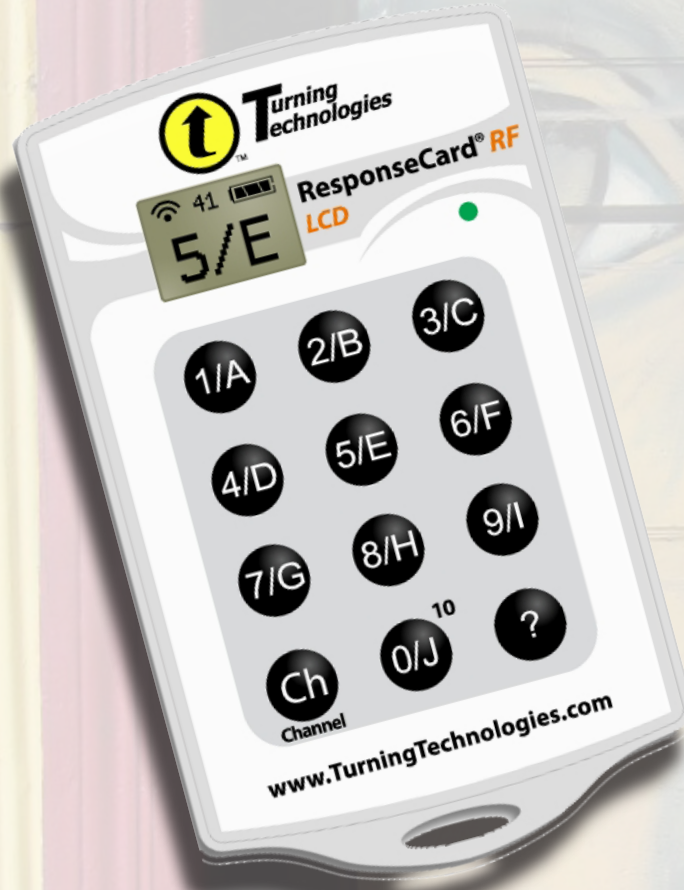


Education is not just about:

- **transferring information**
- **getting students to do what we do**

active participation a must!

PLEASE RETURN CLICKER



1 education

2 PI

3 test



Join now!

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Funding:

National Science Foundation

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Getting every student prepared for every class



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Colorado State University Pueblo
Pueblo, CO, 2 May 2016





CLASS

1st exposure



ROOM

deeper understanding



CLASS

1st exposure



ROOM

deeper understanding



ROOM

1st exposure



CLASS

deeper understanding



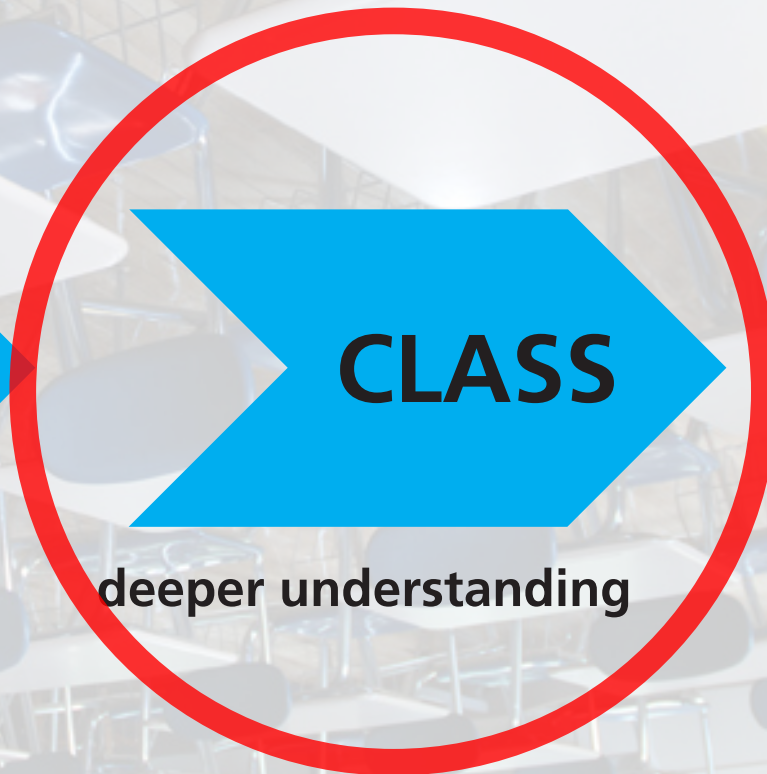
1st exposure



deeper understanding



1st exposure



deeper understanding



1st exposure



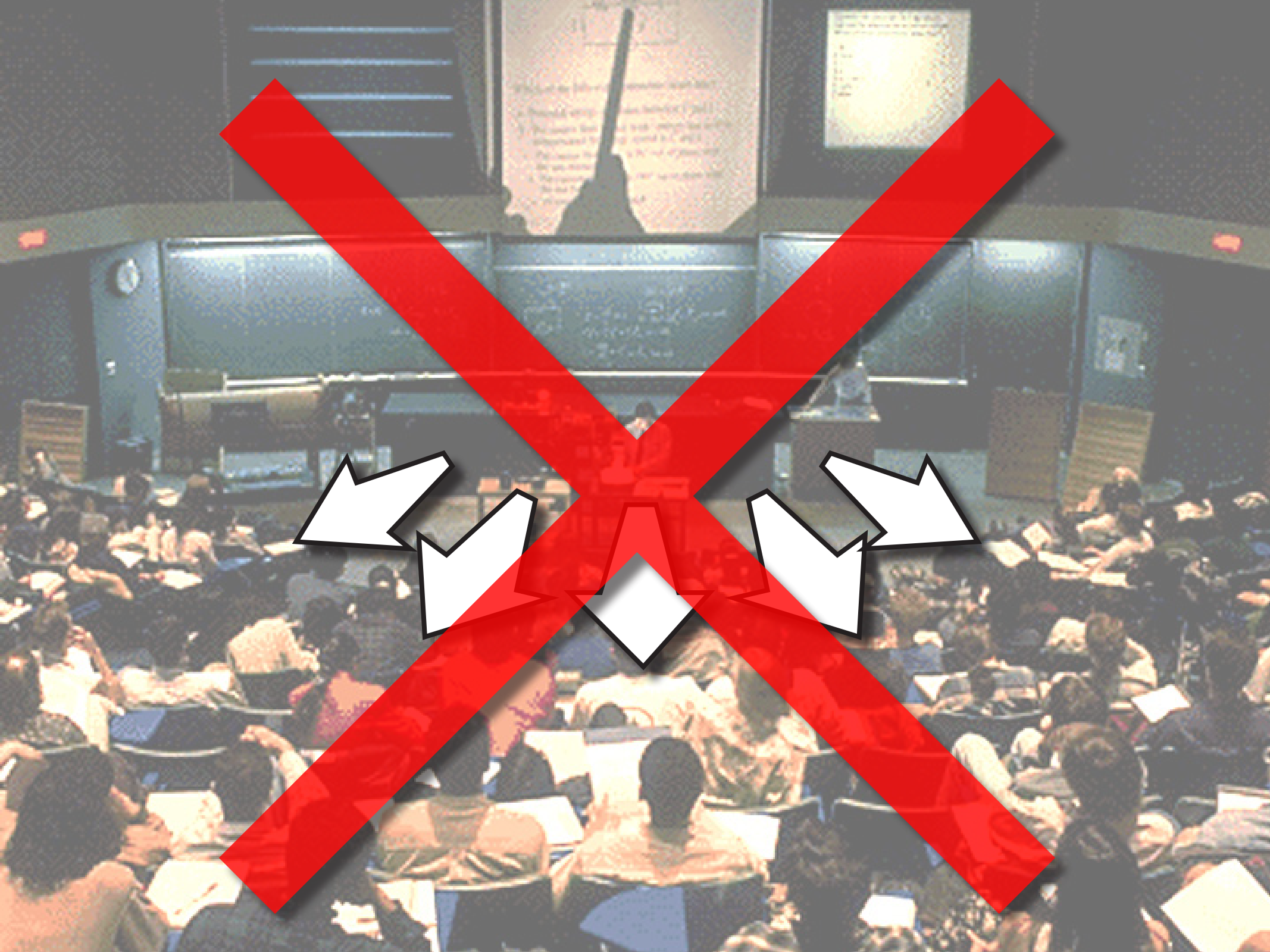
deeper understanding



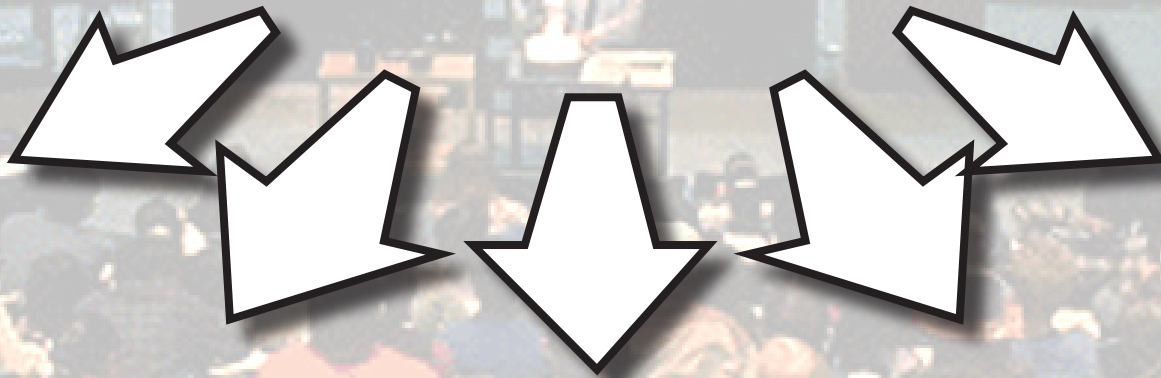
1st exposure



deeper understanding



how to effectively transfer information outside classroom?





but...



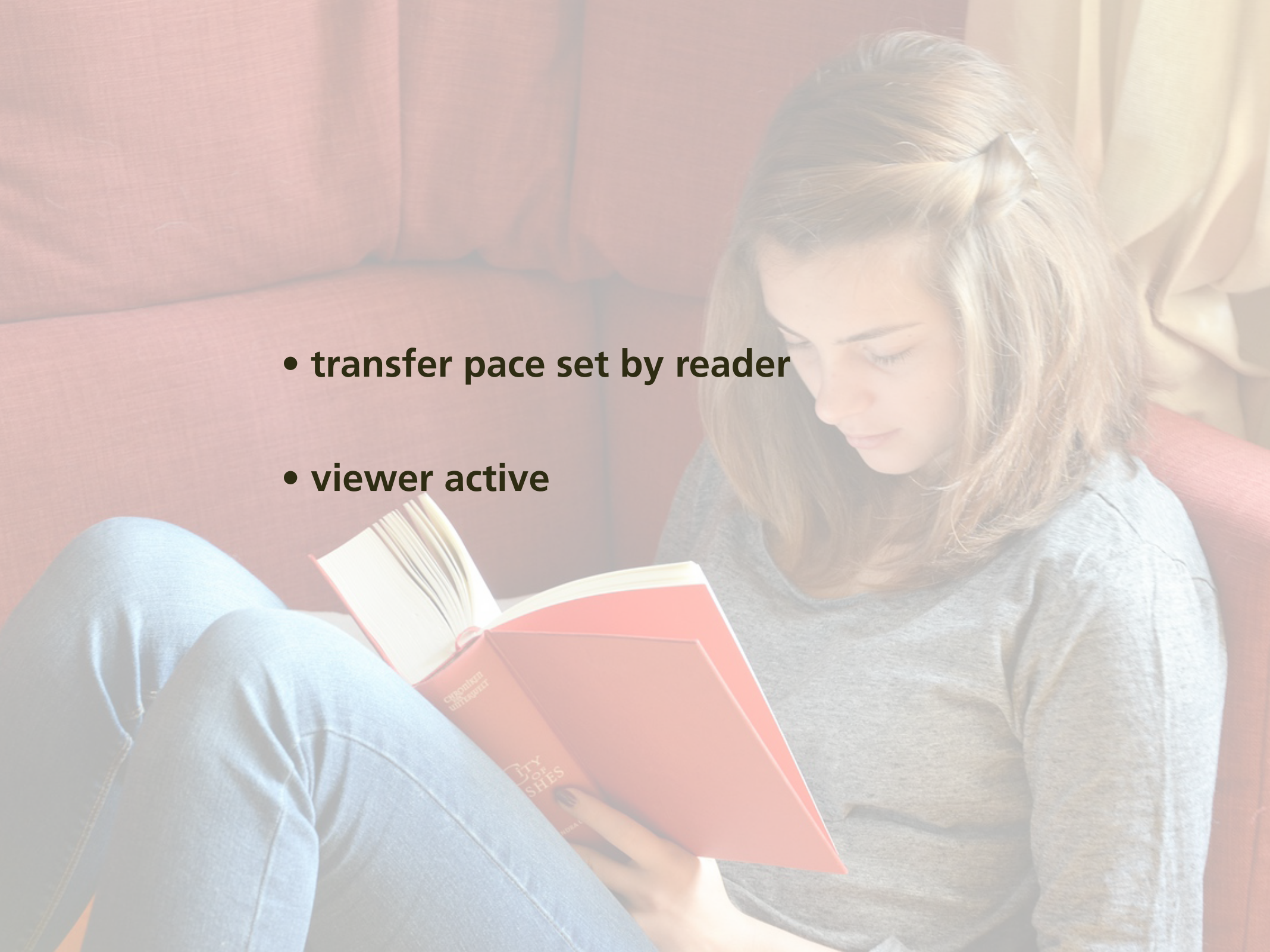
- transfer pace set by video
- viewer passive
- viewing/attention tanks as time passes
- isolated/individual experience






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)

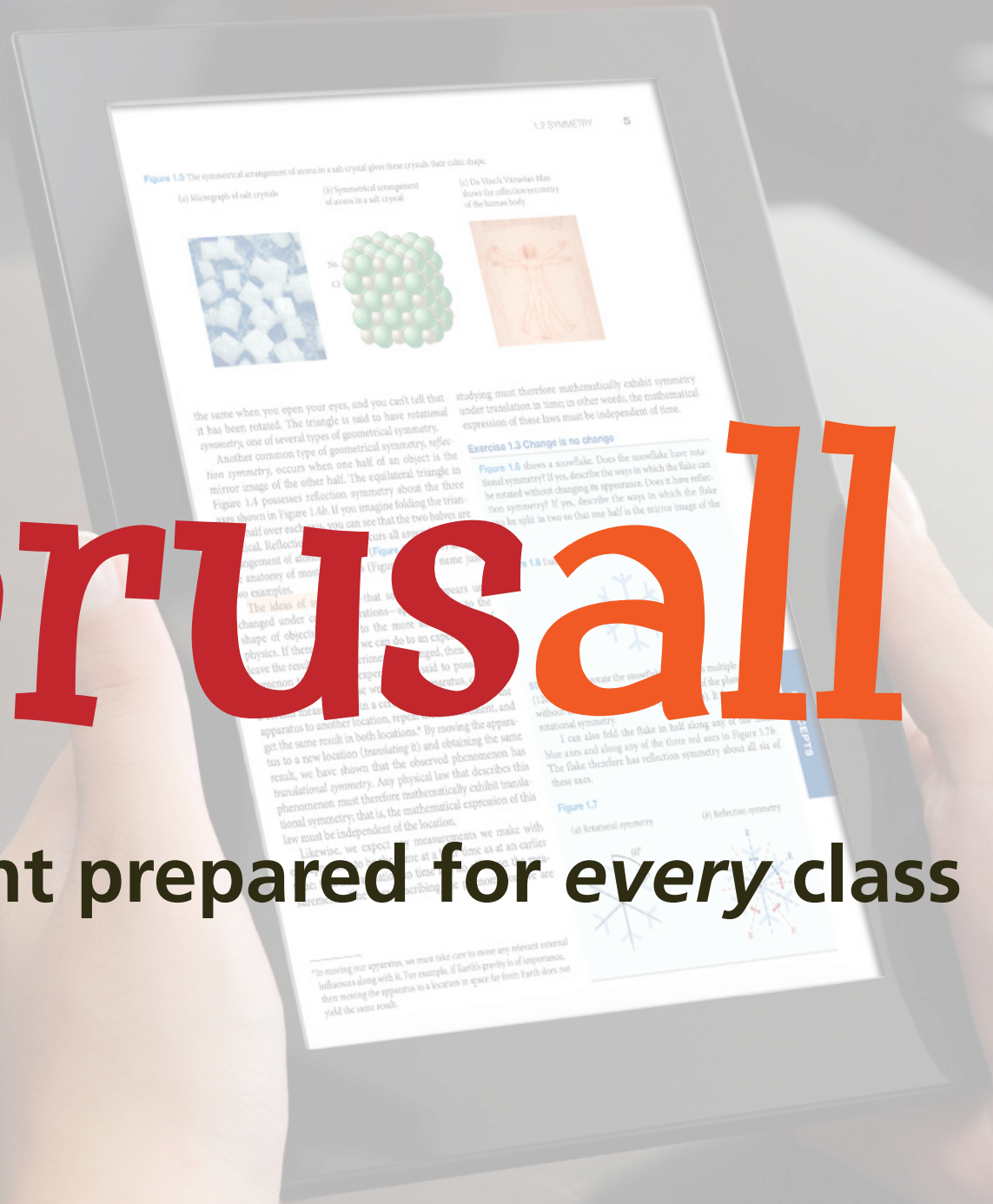
A stylized illustration of a classroom. Several students are seated at rows of desks, facing forward. The students are depicted in various colors (yellow, green, blue, purple, pink, light green) and are holding pens or pencils, suggesting they are taking notes or participating in a lesson. The background is a solid light color.

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 a very ordinary day 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 hardly decreases as the block slides over the smooth surface; and it decreases very rapidly as the block slides over the rough surface. 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—on which the object can slide. 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?

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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 surfaces. The block slides easily over the smooth surface. To bring two objects to rest with respect to each other, the less friction there is, the more difficult it is to come to rest.

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

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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 the track and carts used in the experiments described in this chapter. In your book, the track is shown in Figure 4.2, and 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

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 rougher the surface, the more quickly the velocity decreases 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 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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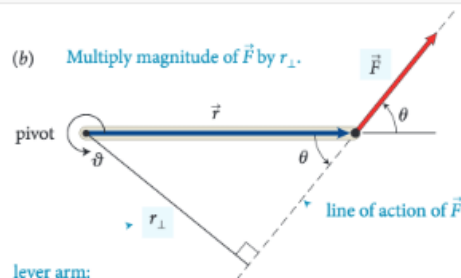
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Nov 1 4:41 pm



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

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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.

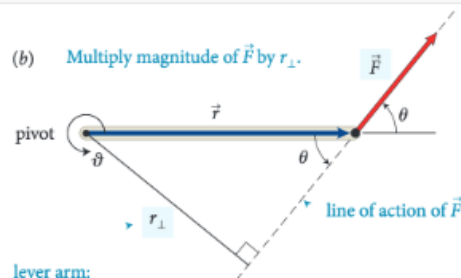


12.2 In the situation depicted in Figure 12.2a, you must continue to exert a force on the seesaw to keep the child off the ground. The force you exert causes a torque on the seesaw, and yet the seesaw's rotational acceleration is zero. How can this be if torques cause objects to accelerate rotationally?

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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Enter your comment or question and press Enter

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"helps me" flag



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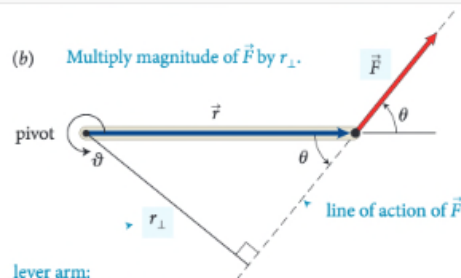
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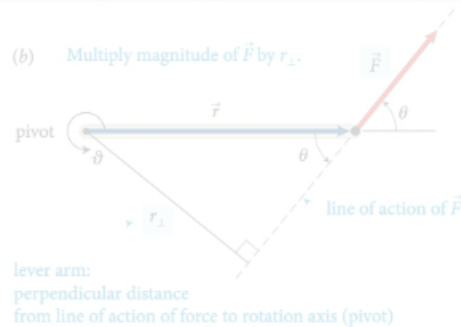
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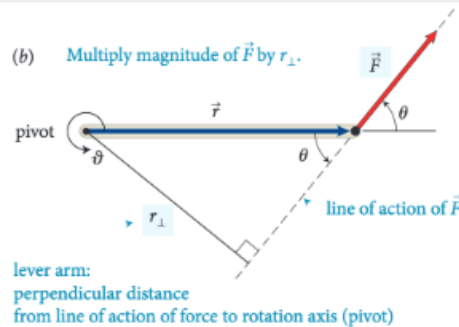
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21 minutes ago, you asked this question on Perusall:

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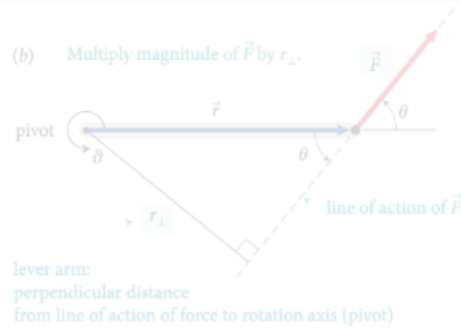
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option 3: mark as answered



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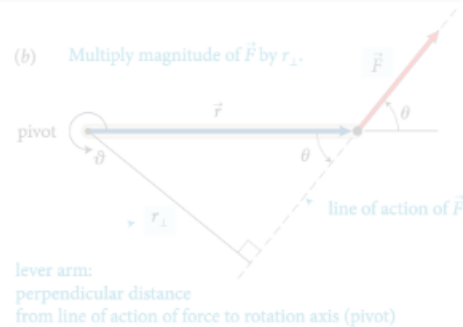
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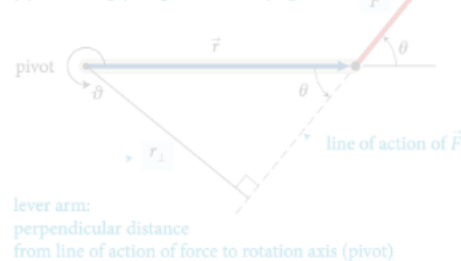
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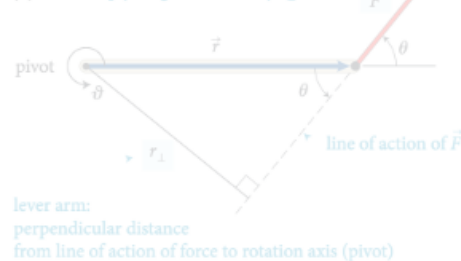
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It's interesting that the white ...

Is the reference frame i... 2

How does force affect ... 2

I was curious about this, t... 3

I understand partially w... 3

In this class, we always emp...

before this wa... 2

The extended free-body d... 4

This just means the net... 3

I don't understand why ... 3

It is important to note that... 2

This reminds me of when we ...

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Orientation-based descriptio...

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How small is small? As ... 3

I think it would be slightly ...

While I believe I underst... 3

(a) The change in rotationa...

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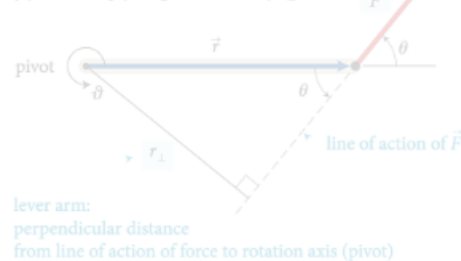
Objects executing motion ar...

Generally, for rotating bod... 2

Does torque have the s... 3

rubric-based assessment

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



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• quality (thoughtful reading & interpretation)

• quantity (minimum 10)

• timeliness (before class)

I don't understand how 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.

I think you may be able to think about the direction separately. So, if you have a 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.

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.

Enter your comment or question and press Enter

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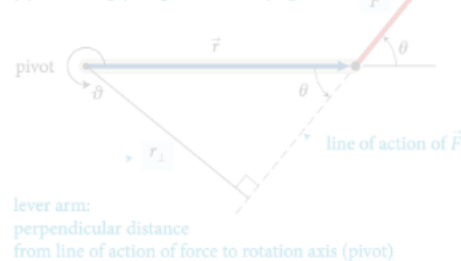
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rubric-based assessment

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



• quality (thoughtful reading & interpretation)

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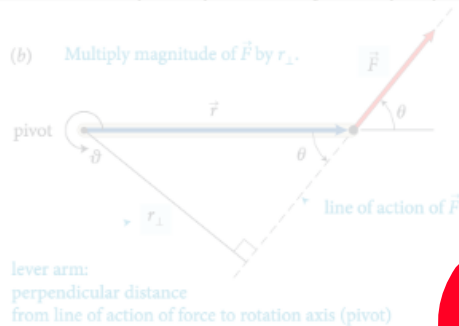
Objects executing motion ar...

Generally, for rotating bod... 2

Does torque have the s... 3

rubric-based assessment

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



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

- quality (thoughtful reading & interpretation)

- quantity (minimum)

- timeliness (before class)

- distribution (not clustered)

over 20,000 annotations!

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 this force about the left end of the rod is zero. If I choose the counterclockwise direction as positive for rotation, \vec{F}_2 causes a negative torque about the left end of the rod; the force \vec{F}_2 is applied at a point a distance r_2 from the left end of the rod, and the lever arm distance is r_2 . The lever arm distance of \vec{F}_3 about the left end of the rod is r_3 , and the torque caused by this force is equal to the magnitude of the force F_3 multiplied by r_3 . The net torque about the left end of the rod is the sum of the torques caused by the three forces. We obtain $\tau_{\text{net}} = -F_2 r_2 + F_3 r_3$. The result is the same if we choose the right end of the rod as the pivot, and the sum of the torques about the right end is zero, just like the sum of the torques about the left end. You can repeat the calculation for the torques about the right end of the rod for 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 choose any point as the pivot point. For a rotating object we choose a reference point that is convenient for the calculation. As you have seen, we do not need to know any information about the reference point when calculating the torque about a point at the reference point. We can calculate the torque about any point by choosing that point as the pivot point.

Example 12.2 Torques on lever

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?

On the left, we see th...

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Is it better to frame i... 2

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(a) The change in rotationa...

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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. In general, for any 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 where a force is exerted, we can eliminate that force from the calculation.

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how do you process all of that??

- timeliness (before class)

- distribution (not clustered)

On the very left, we see th...

It's interesting that the white ...

Is the reference frame i... 2

How does force affect ... 2

I was curious about this, t... 3

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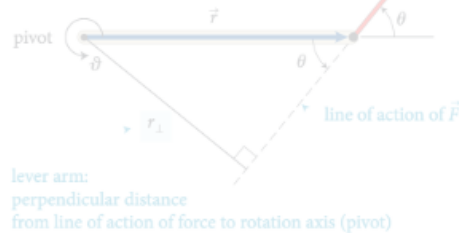
Objects executing motion ar...

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rubric-based assessment

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



- quality (though future could interpret)

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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 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, and \vec{F}_3 is 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_2 , and 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 $(\vec{F}_1 + \vec{F}_2 + \vec{F}_3) \cdot \vec{r}_0$. 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. ✓

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For a static equilibrium problem, you can 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.



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The extended free-body d... 4

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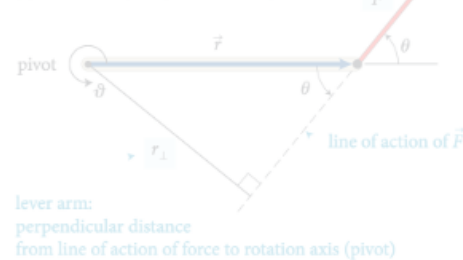
Objects executing motion ar... 2

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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.

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 convention for the sign is to explain how to choose the direction of rotation.

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.

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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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Gradebook

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[REDACTED]		1		
[REDACTED]				
[REDACTED]		0		
[REDACTED]		3		

Total number of annotations **16**

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

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

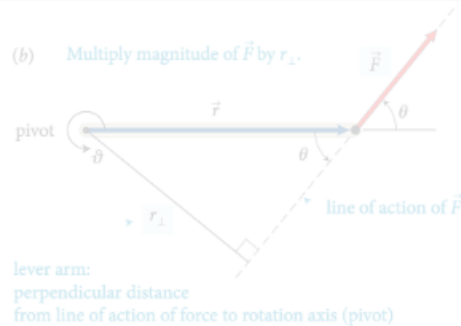
2 = demonstrates thorough and thoughtful reading and insightful interpretation of the reading, 1 = demonstrates reading, but no (or only superficial) interpretation of the reading, 0 = does not demonstrate any thoughtful reading or interpretation

Distribution of annotations **3.8**

0 = clustered, 5 = evenly distributed throughout assignment

Assignment score **1**

scores range from 0 to 3



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

reference point
 \vec{F}_1
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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.

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.

Enter your comment or question and press Enter

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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? 2
- SB Using the right hand rule, I believe the answer is D. Is that correct? 3
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? 2
- AK Can someone explain why this type of bacteria knows what direction the earth's magnetic fields are facing? 3
- 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. 3
Show more...

motivating factors

Intrinsic:

• social interaction

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



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

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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

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

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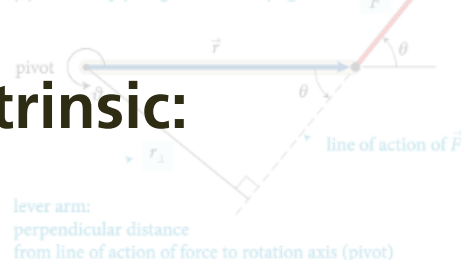
Enter your comment or question and press Enter

motivating factors

Intrinsic:

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

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



lever arm:

perpendicular distance
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motivating factors

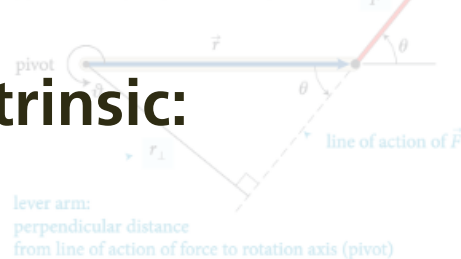
Intrinsic:

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

Extrinsic:

- assessment (fully automated)

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



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motivating factors

"I think the Perusall app and annotation system is way better than just reading a textbook normally... I've been reading for almost four hours now and haven't gotten bored"

Harvard student

The screenshot displays the Perusall app interface. At the top, the browser address bar shows 'app.perusall.com'. The app header includes the 'Perusall' logo, the course 'AP50 Fall 2015 » Chapter 12', and the user 'Eric Mazur'. The main content area shows a physics textbook page titled 'torque' with a diagram of a lever and text explaining torque. The diagram shows a horizontal rod with a pivot at the left end. A force \vec{F} is applied at the right end, making an angle θ with the horizontal. The lever arm distance is r_1 . The text explains that the lever arm distance must 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}_{pt} 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}_{pt} is r_1 . The torque caused by \vec{F}_2 is $-(r_1 + r_2)F_2$ and the torque caused by \vec{F}_{pt} is $r_1 F_1$. Taking into account the signs of the torques, we find that the sum of the torques about the left end of the rod is $-(r_1 + r_2)F_2 + r_1 F_1 = 0$. This is the same result as before. Exercise 12.1 shows that the sum of the torques about the right end of the rod is zero, just like the sum of the torques about the left end. You can choose any reference 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. 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. Example 12.2 Torques on lever 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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motivating factors

"It makes the book fun to read..."

All the other students on my floor are disappointed their Prof isn't using Perusall because they don't read the book."

Ohio State student

The screenshot displays the Perusall interface for a physics textbook chapter on torque. The top navigation bar includes the Perusall logo, course information (AP50 Fall 2015 » Chapter 12), and user details (Page 284, Eric Mazur). The main content area shows a textbook page with a diagram of a lever arm and a list of student comments. The diagram illustrates a lever arm of length r at an angle θ to the horizontal, with a force F applied at the end. The lever arm distance is labeled r_1 and the line of action of the force is labeled F . The diagram is labeled (b) Multiply magnitude of F by r_1 .

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

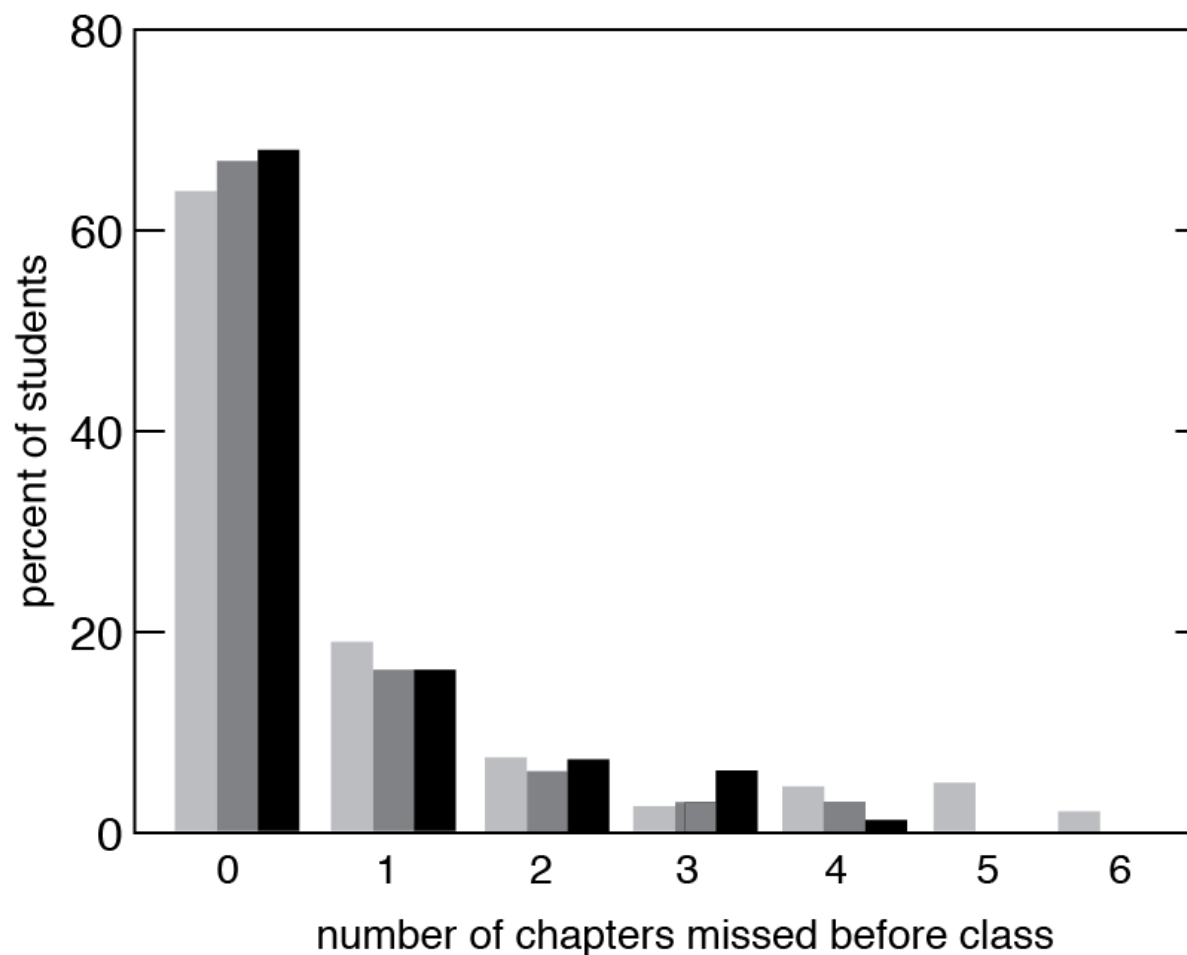
\vec{F}

reference point

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Enter your comment or question and press Enter

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research data

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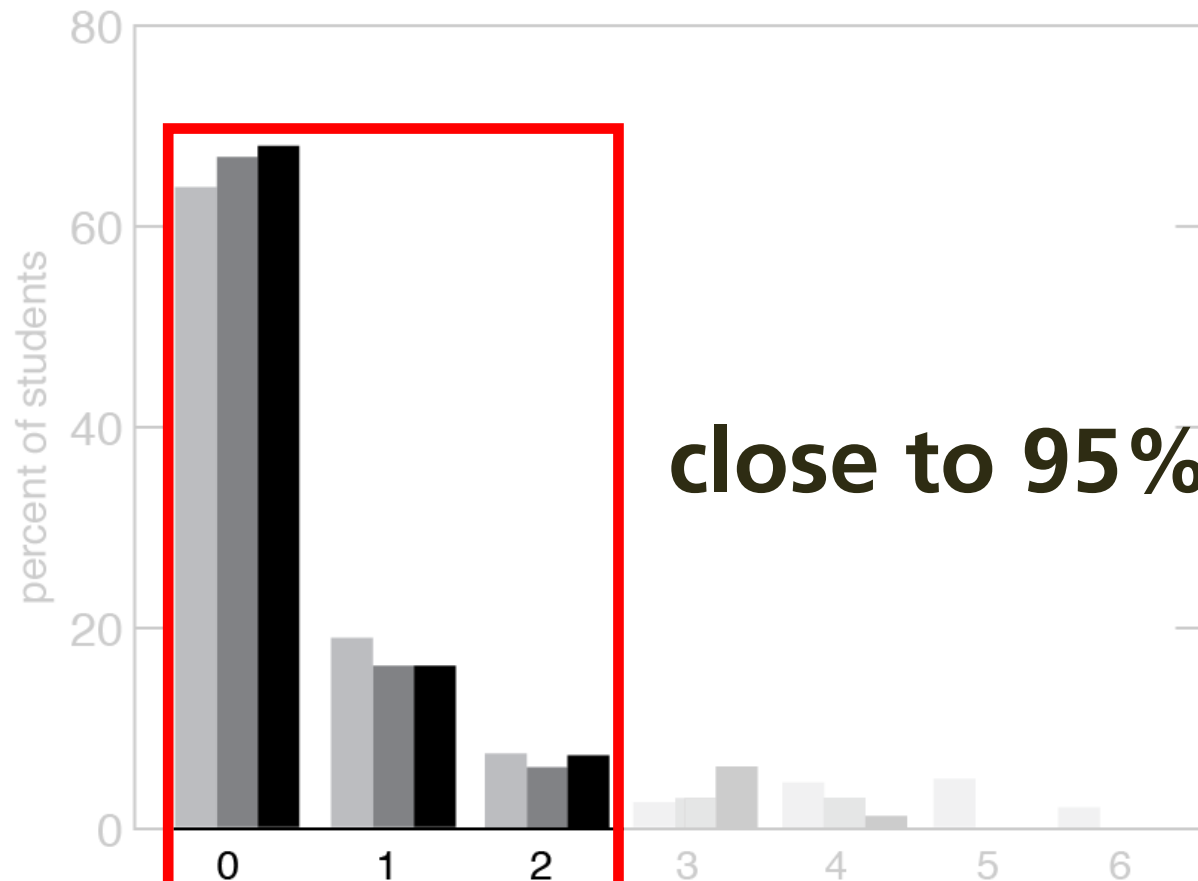
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close to 95%!

number of chapters missed before class

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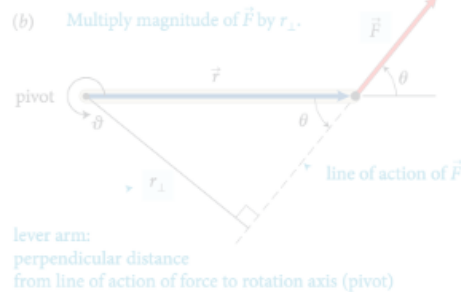
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every student prepared for every class

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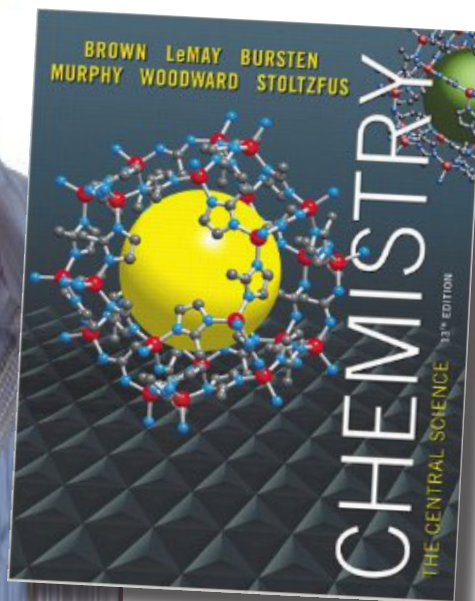
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CHEM1210: General Chemistry

Matt Stoltzfus
Ohio State University

525 students

Brown Lemay 13th ed (Pearson)

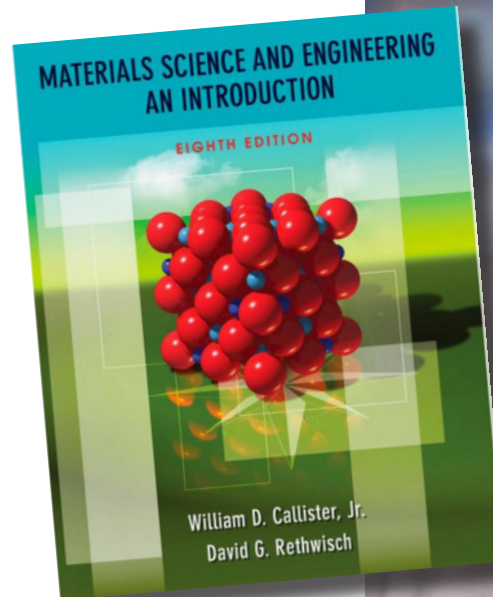


MSE220 : Introduction to Materials and Manufacturing

Steve Yalisove
University Michigan

74 students

McCallister 8th ed (Wiley)



additional research data

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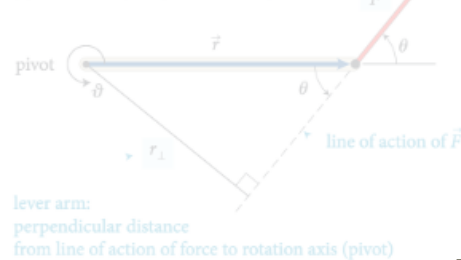
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Perusall AP50 Fall 2015 » Chapter 12: Rotational Motion » Torque

Page 284 Eric Mazur

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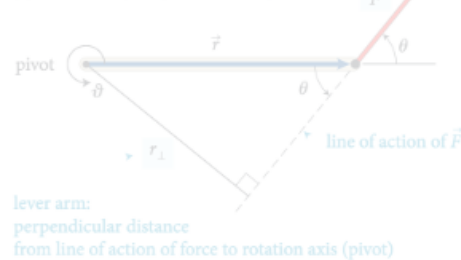
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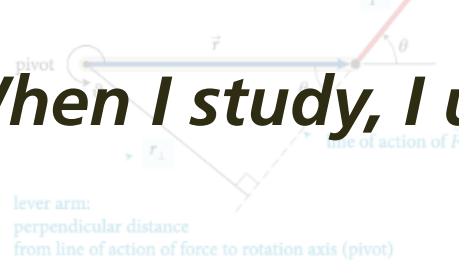
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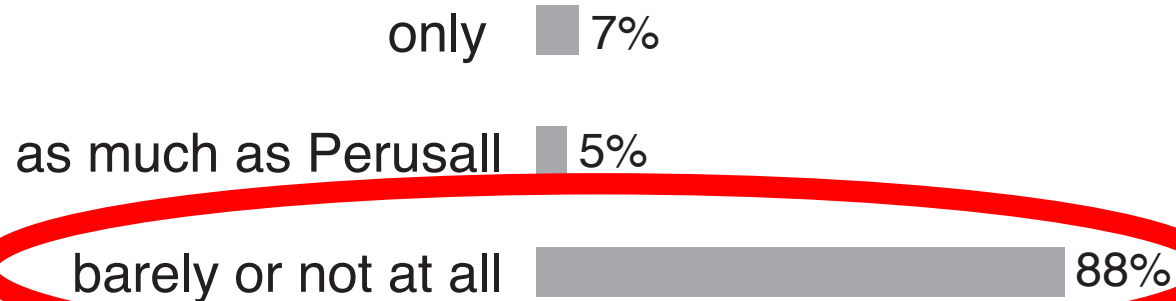
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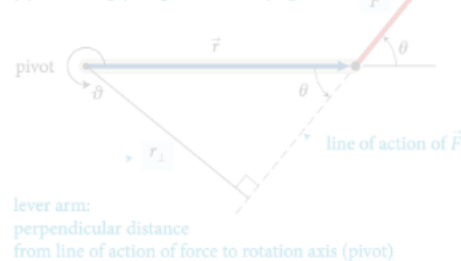
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Generally, for rotating bod... 2

Does torque have the s... 3

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

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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Students...

- read the textbook
- learn how to read
- learn how to read critically
- participate in a collaborative experience

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

lever arm:
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Lever arm distance has 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, 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 useful choice because the pivot is the point about which the rod rotates. 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.

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- **get more out of their classes**

Benefits to instructors

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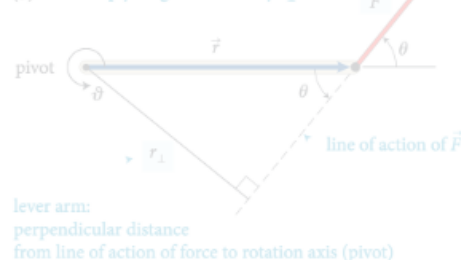
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• time recovery

CONCEPTS

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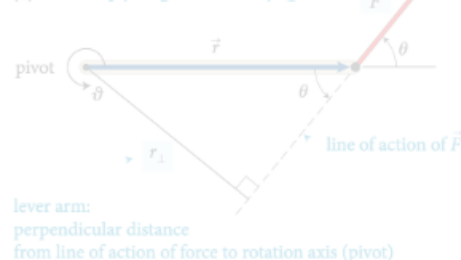
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Benefits to instructors

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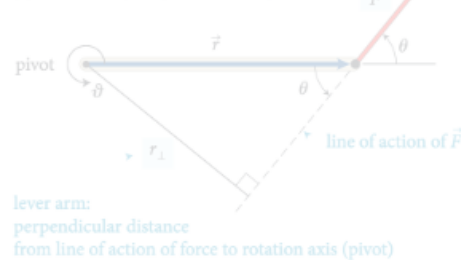
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The lever arm distances must now be determined relative to the left end of the rod. The lever arm distance of force \vec{F}_1 to this point is zero, and so the torque caused by that force about the left end of the rod is zero. If I choose counterclockwise 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 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:

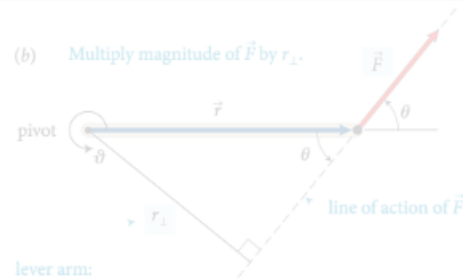
For a stationary object we can choose any reference point we like to calculate torques. It pays to choose a reference point that simplifies the calculation. As you have seen, we do not need to consider any force that is exerted at the reference point. So, by putting the reference point at the point of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

Figure 12.7 A seesaw is a stationary object. The ground is the reference point. 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}_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?

(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 magnitudes of the forces times their lever arm distances. We use the word "torque" to mean the product of the magnitude of the force and its lever arm distance. If the net torque on an object is zero, its 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

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 $(F_1 + F_2)r_1 - (F_1 + F_2)(r_1 + r_2) = 0$. 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:

If the net torque on an object is zero, its rotational acceleration is zero, and so its rotational velocity and angular momentum change. 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}_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?

follow up questions?
support@perusall.com

Hands-on with Peer Instruction



@eric_mazur



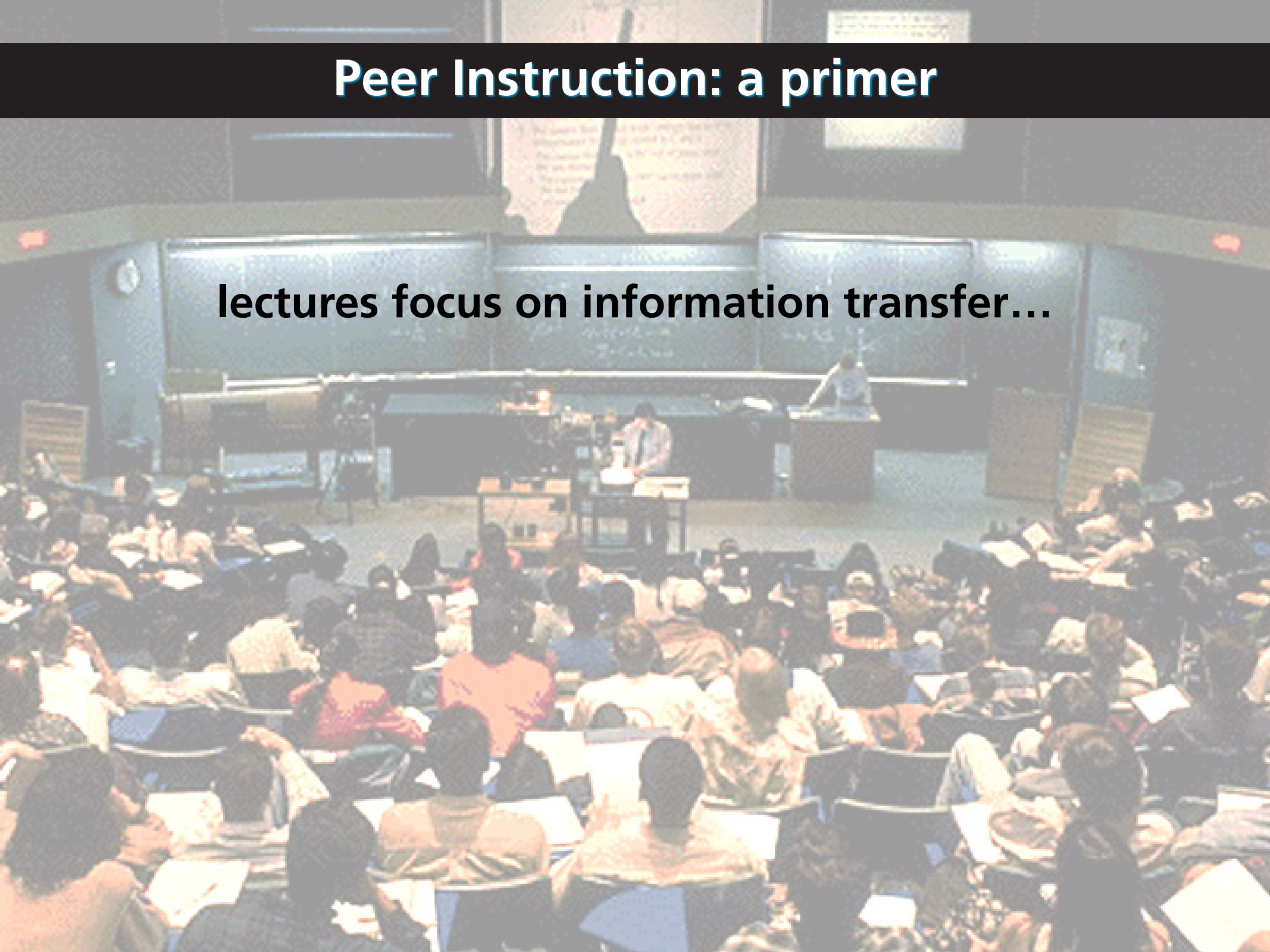
Colorado State University Pueblo
Pueblo, CO, 2 May 2016



ERIC MAZUR

Peer Instruction: a primer

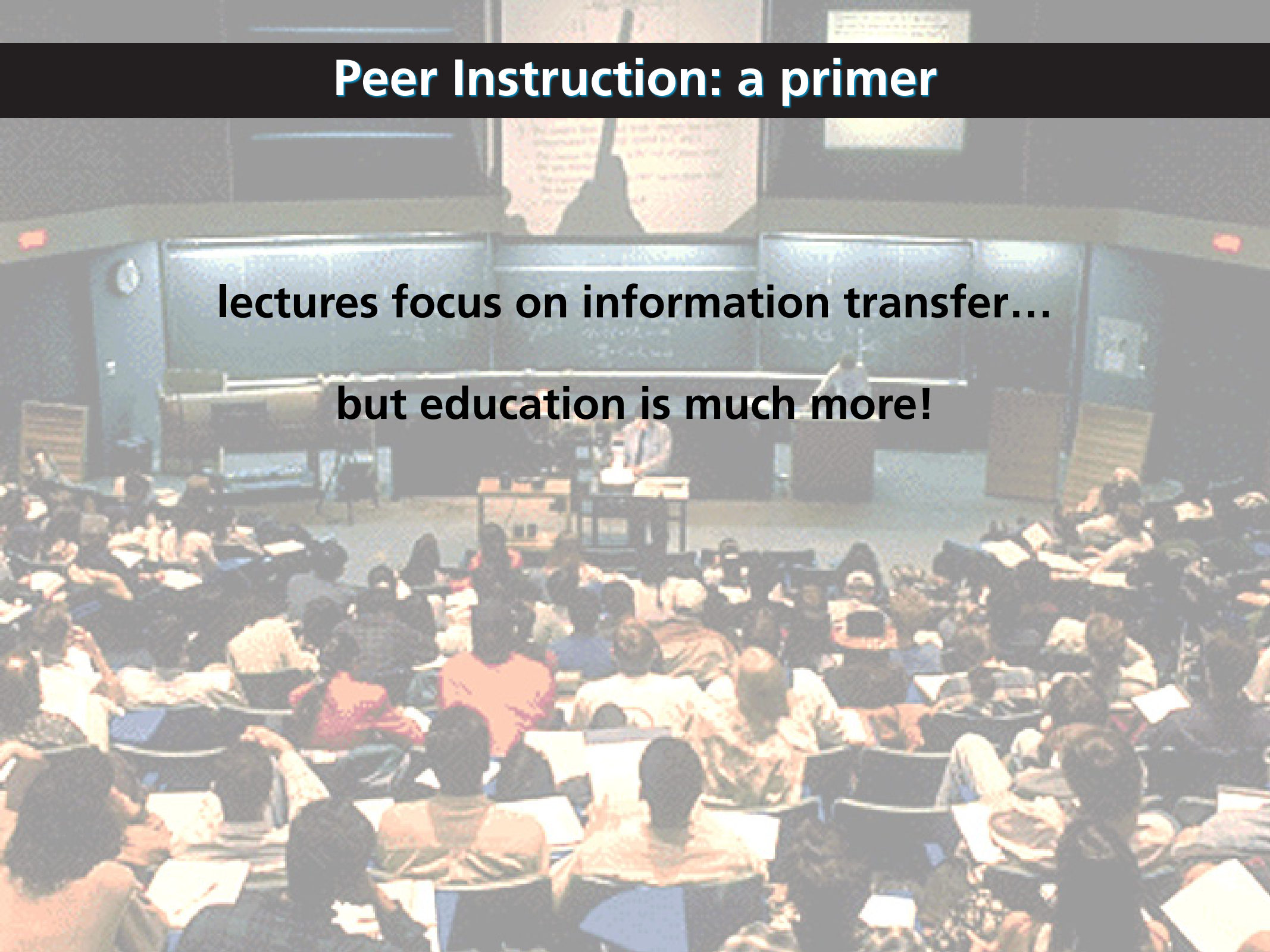
lectures focus on information transfer...



Peer Instruction: a primer

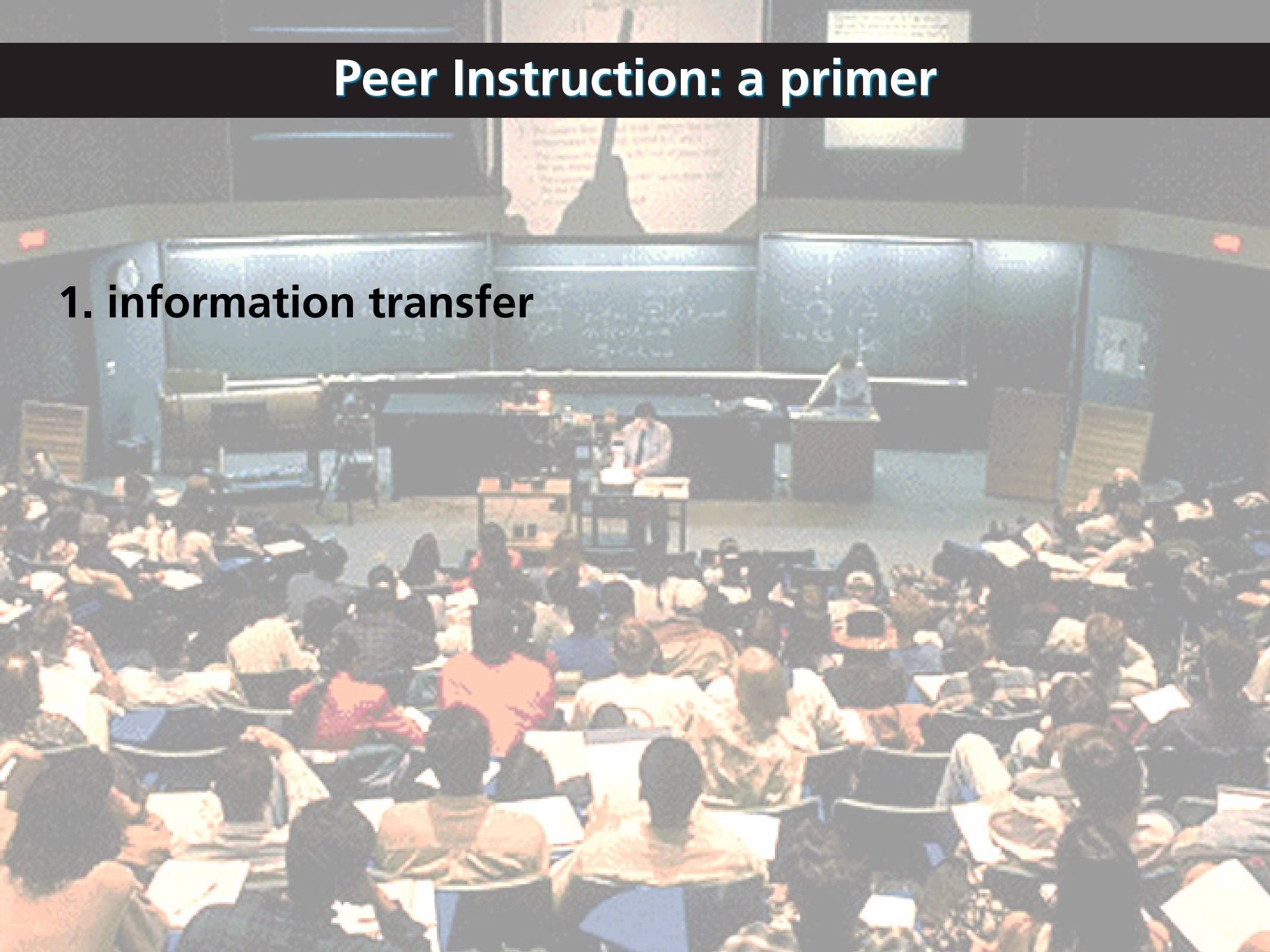
lectures focus on information transfer...

but education is much more!



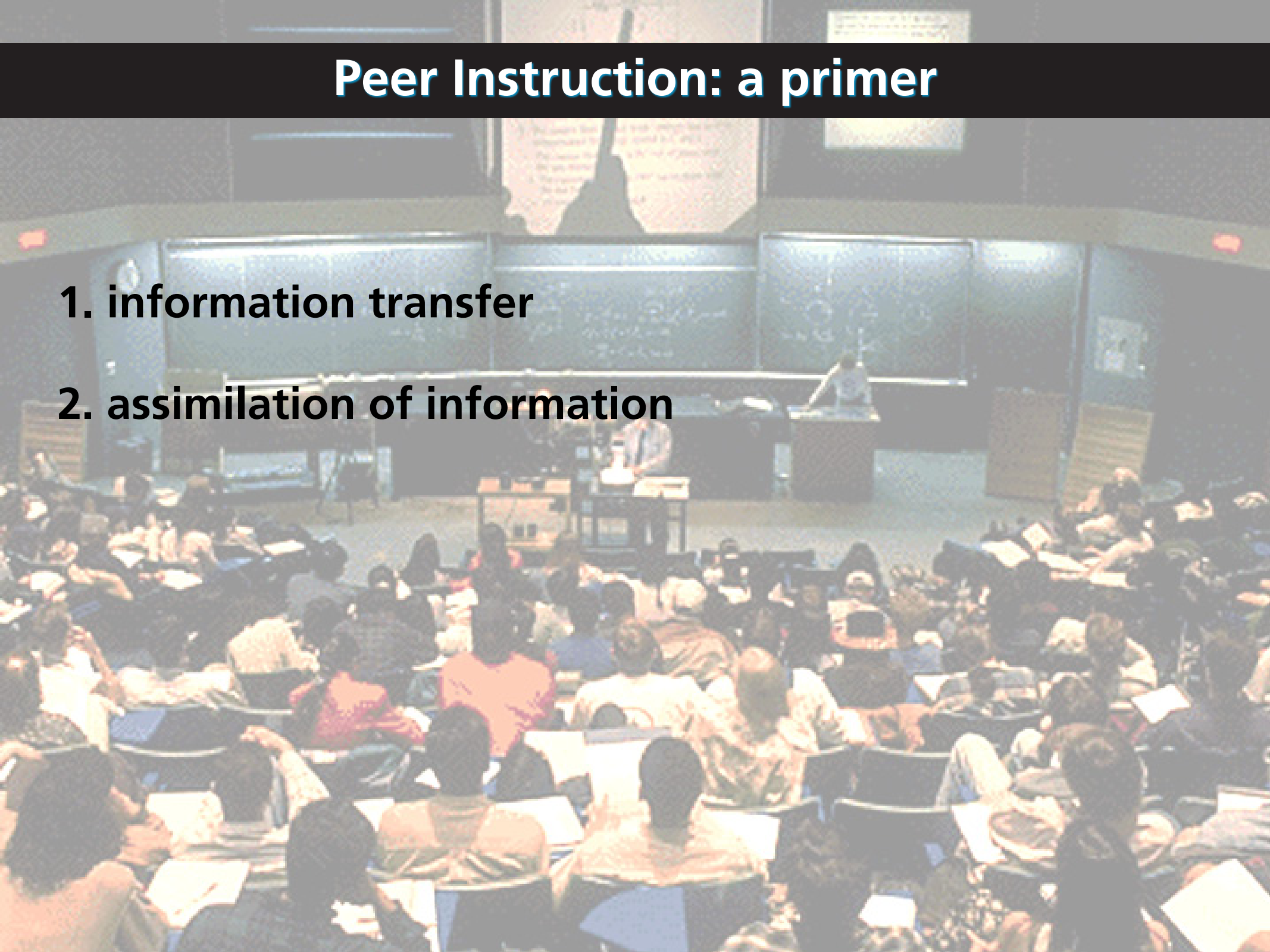
Peer Instruction: a primer

1. information transfer



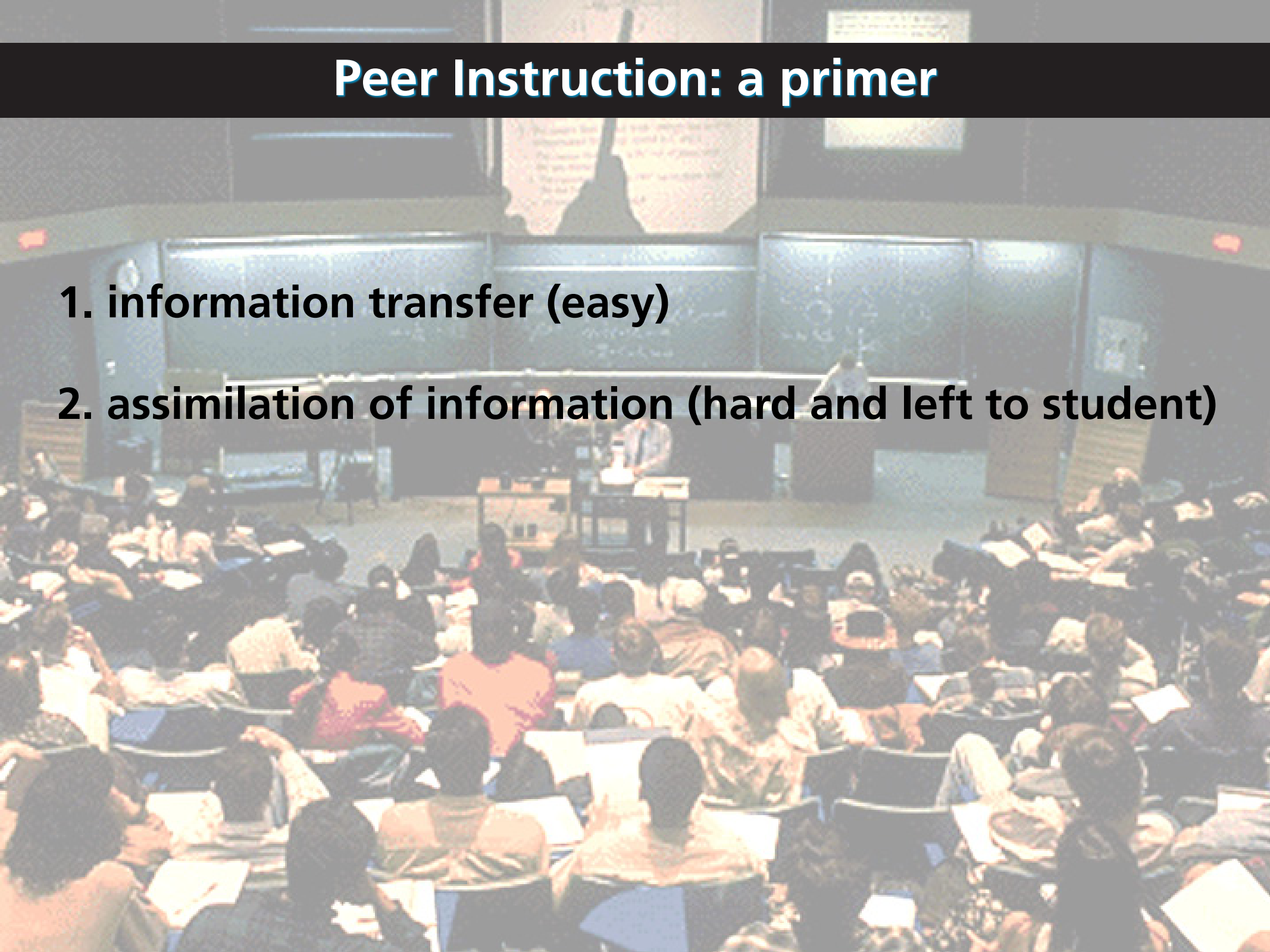
Peer Instruction: a primer

1. information transfer
2. assimilation of information



Peer Instruction: a primer

1. information transfer (easy)
2. assimilation of information (hard and left to student)



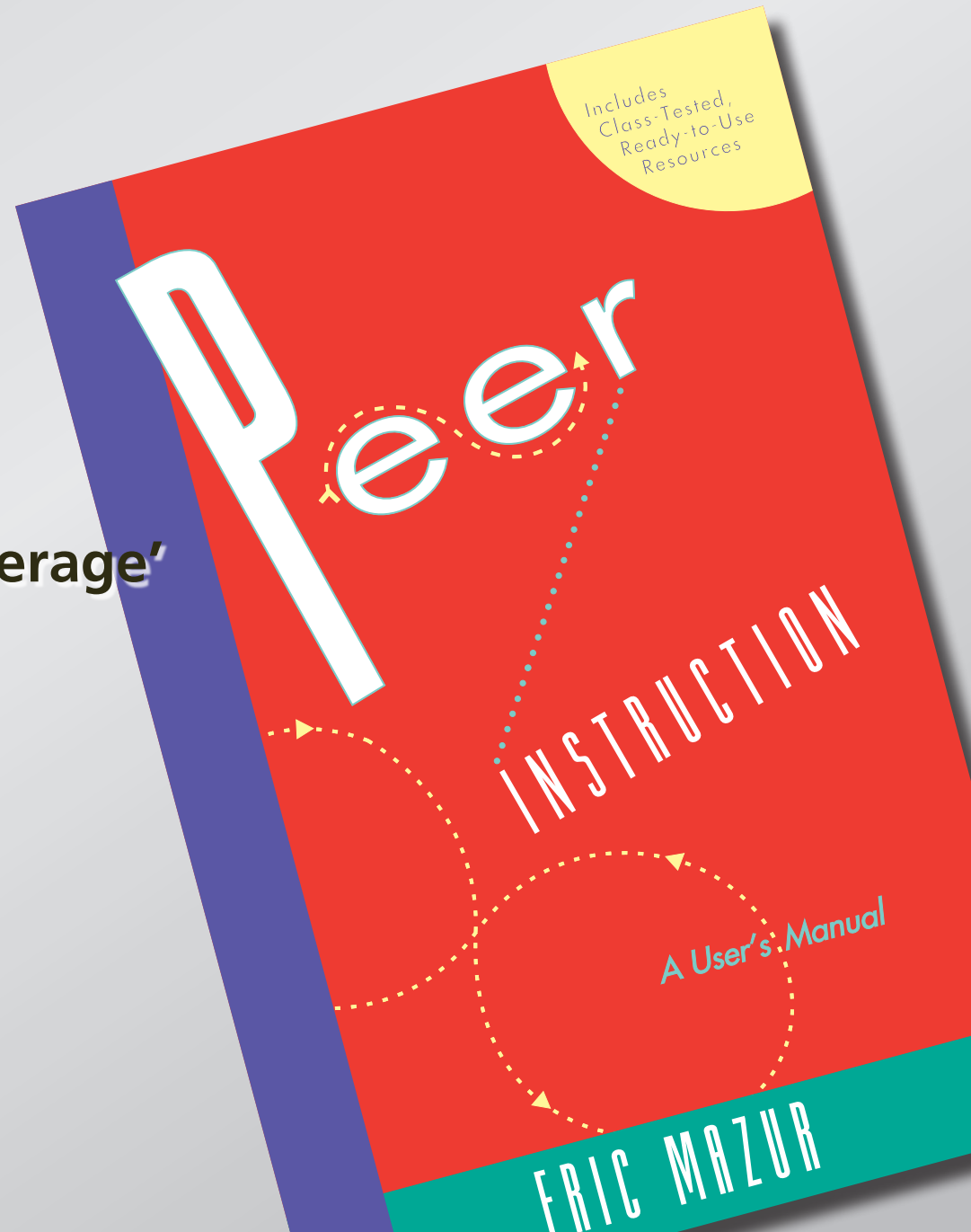
Peer Instruction: a primer

Solution: move information transfer out of classroom!

Peer Instruction: a primer

Main features:

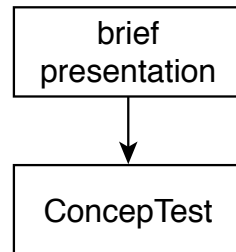
- pre-class reading
- in-class: depth, not 'coverage'
- ConcepTests



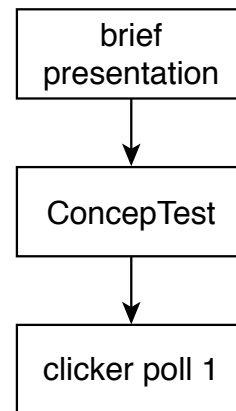
Peer Instruction: a primer

brief
presentation

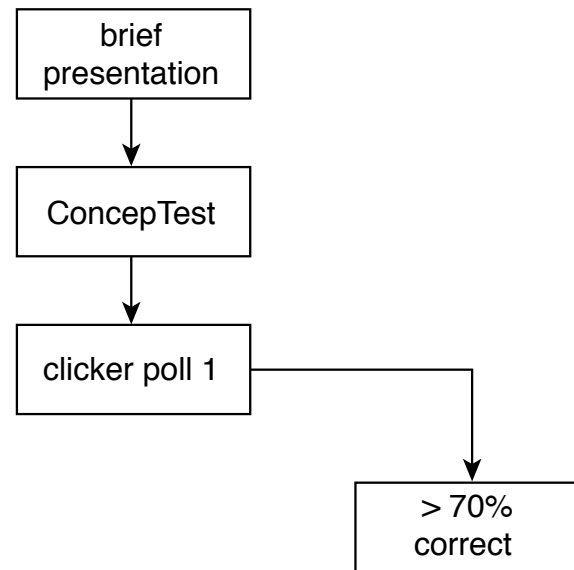
Peer Instruction: a primer



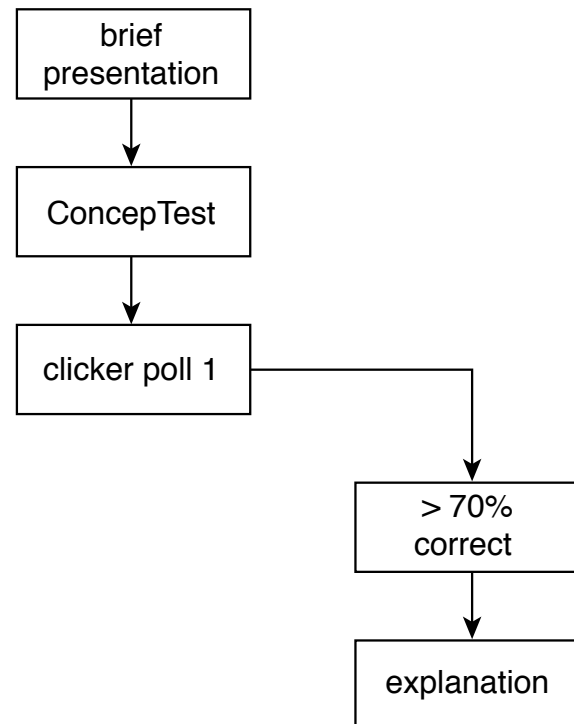
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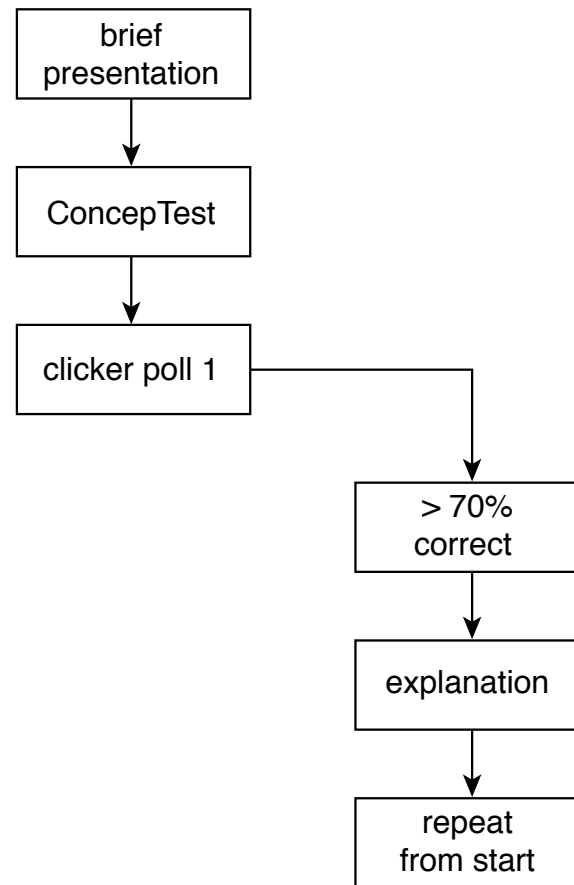
Peer Instruction: a primer



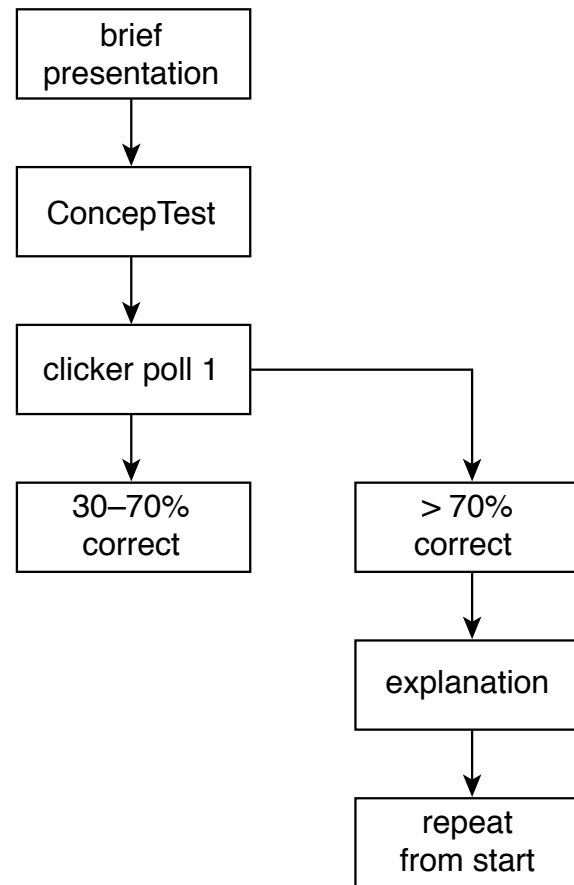
Peer Instruction: a primer



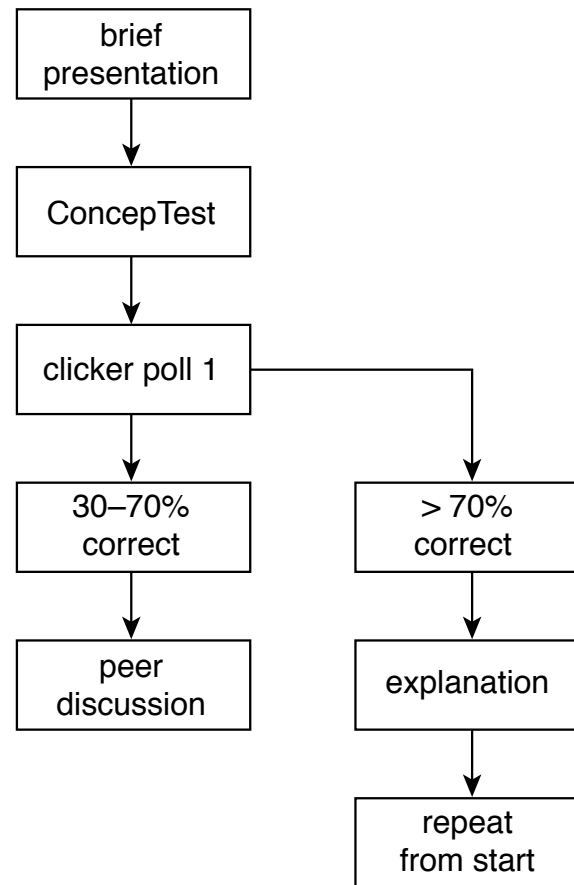
Peer Instruction: a primer



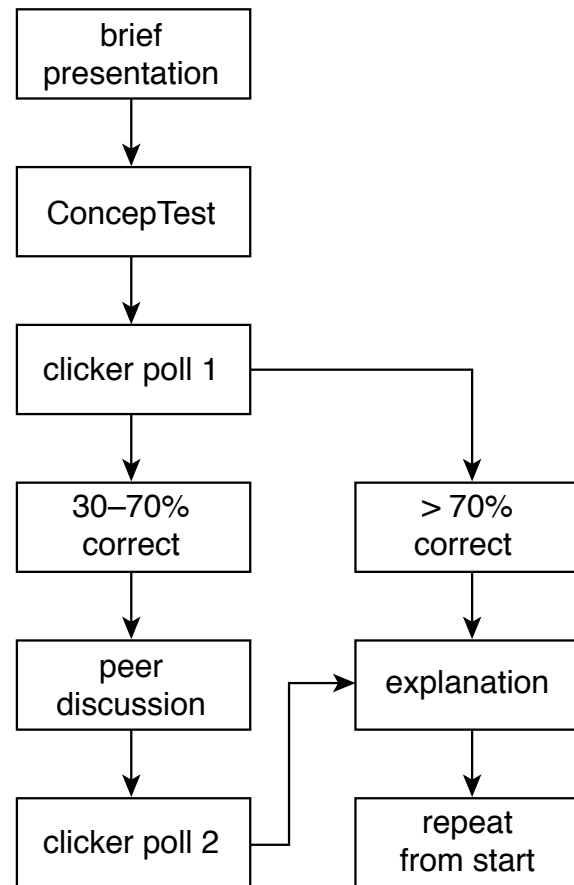
Peer Instruction: a primer



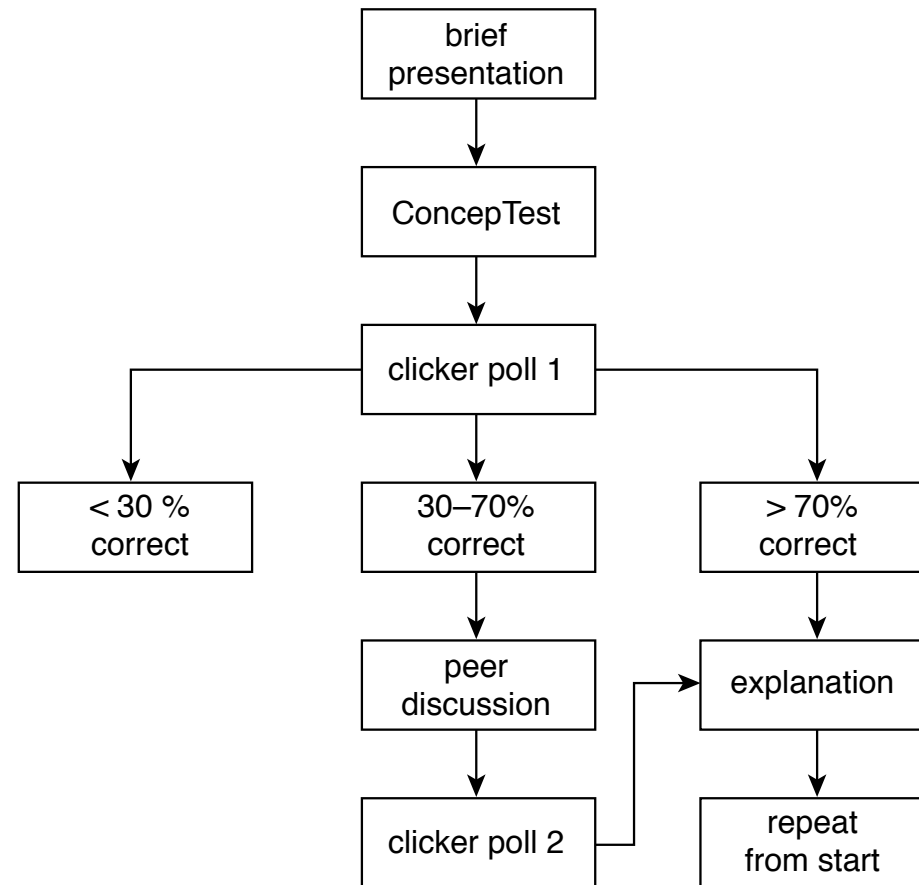
Peer Instruction: a primer



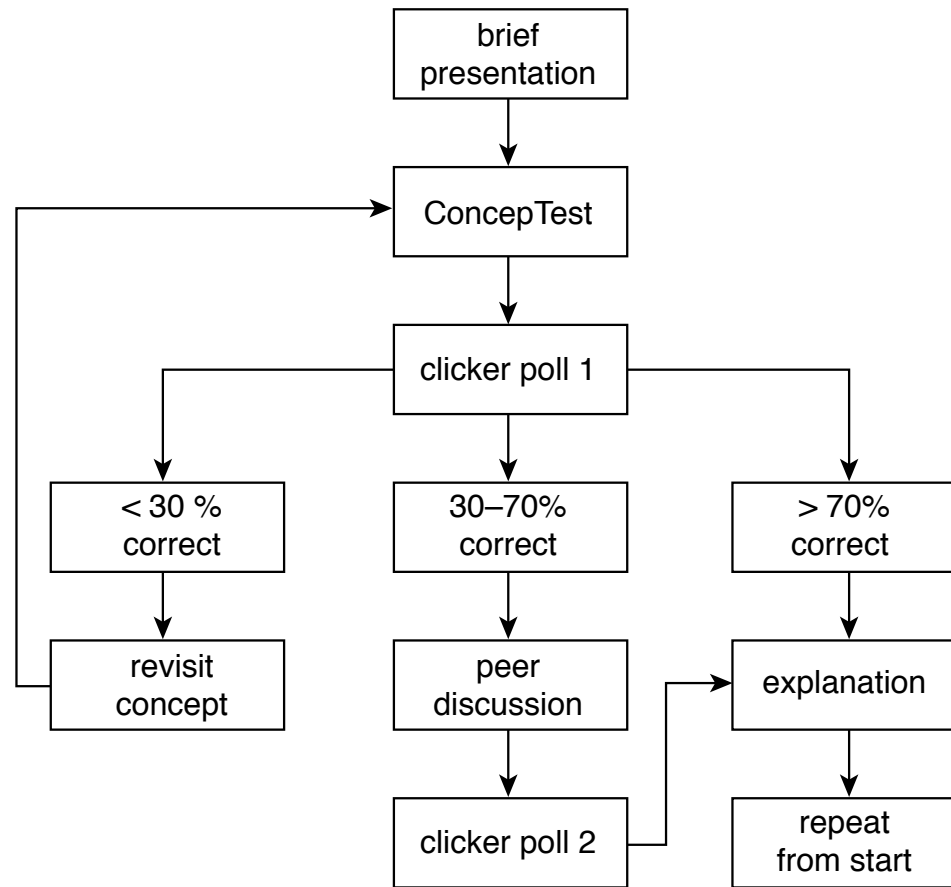
Peer Instruction: a primer



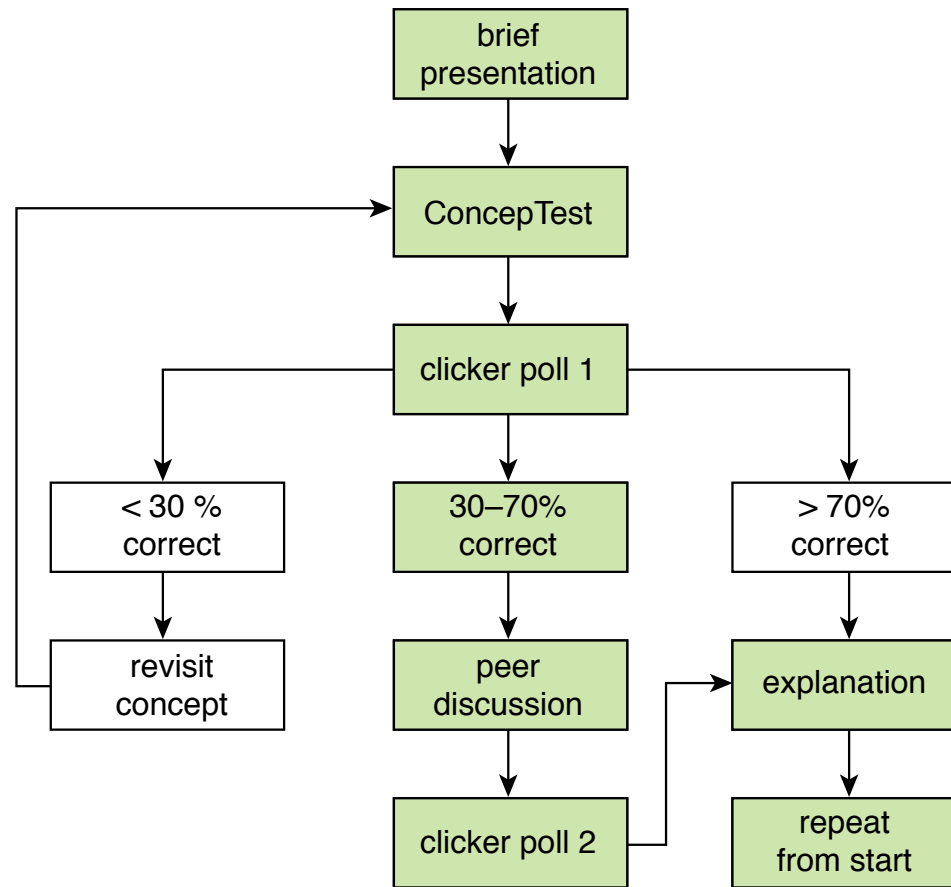
Peer Instruction: a primer



Peer Instruction: a primer



Peer Instruction: a primer



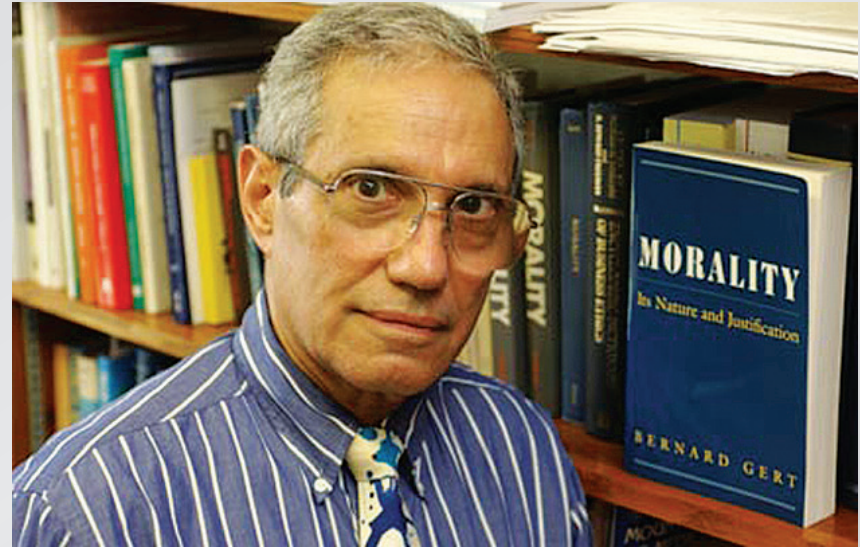
Frequently Asked Questions

*“Can this method be used in my class,
where questions don’t necessarily have right answers?”*

Let's try it!

Bernard Gert (1934 – 2011)

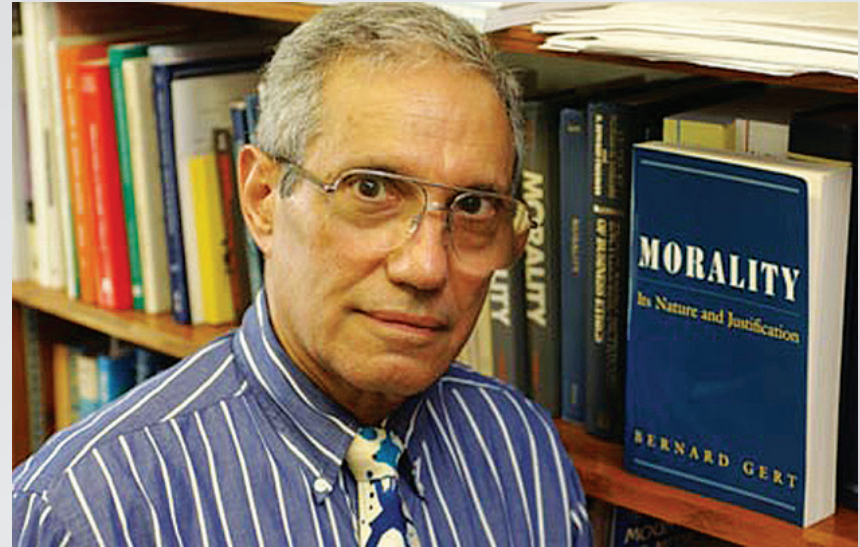
**Moral philosopher
Professor at Dartmouth**



Let's try it!

Bernard Gert (1934 – 2011)

**Moral philosopher
Professor at Dartmouth**



“Morality is an informal public system applying to all rational persons, governing behavior that affects others, and includes what are commonly known as the moral rules, ideals, and virtues and has the lessening of evil or harm as its goal.”

Let's try it!

Bernard Gert's moral system created by 10 rules:

- 1. Do not kill**
- 2. Do not cause pain**
- 3. Do not disable**
- 4. Do not deprive of freedom**
- 5. Do not deprive of pleasure**
- 6. Do not deceive**
- 7. Keep your promises**
- 8. Do not cheat**
- 9. Obey the law**
- 10. Do your duty (as required by job, circumstances).**

Let's try it!

Heinz's wife was near death, and her only hope was a drug that had been discovered by a pharmacist who was selling it for an exorbitant price. The drug cost \$20,000 to make, and the pharmacist was selling it for \$200,000. Heinz could only raise \$50,000 and insurance wouldn't make up the difference. He offered what he had to the pharmacist, and when his offer was rejected, Heinz said he would pay the rest later. Still the pharmacist refused. In desperation, Heinz broke into the store and stole the drug.

Let's try it!

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Should Heinz have broken into the store to steal the drug for his wife?

Let's try it!

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Should Heinz have broken into the store to steal the drug for his wife?

- 1. Yes**
- 2. No**



Let's try it!

Bernard Gert's moral system created by 10 rules:

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8. Do not cheat
9. Obey the law
10. Do your duty (as required by job, circumstances).

Should Heinz have broken into the store to steal the drug for his wife?

1. Yes
2. No



Frequently Asked Questions

“How do I move information transfer out of classroom?”

Frequently Asked Questions

“How can I be sure that my students will prepare for class?”

Getting students to read

Students do not come to class prepared, because...

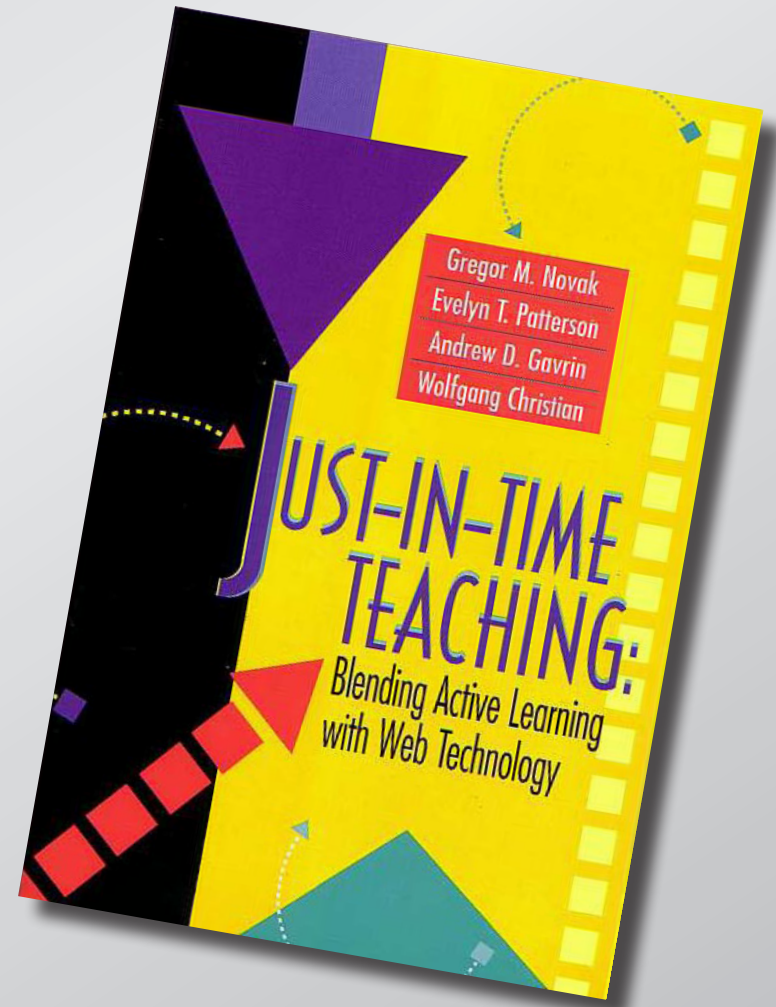
- 1. they don't have time.**
- 2. they are not motivated to learn.**
- 3. their instructors take away the incentive.**
- 4. they do not have the requisite skills.**
- 5. of some other reason.**
- 6. They do come prepared in my class!**

(select what you consider to be the main reason)

Getting students to read

Just-in-time-Teaching (JiTT)

www.jitt.org



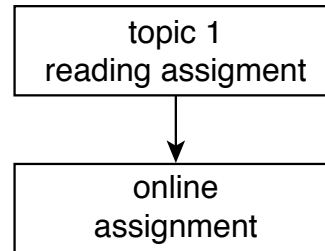
Getting students to read

JiTT workflow

topic 1
reading assignment

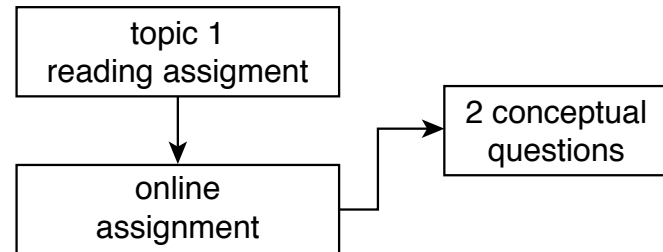
Getting students to read

JiTT workflow



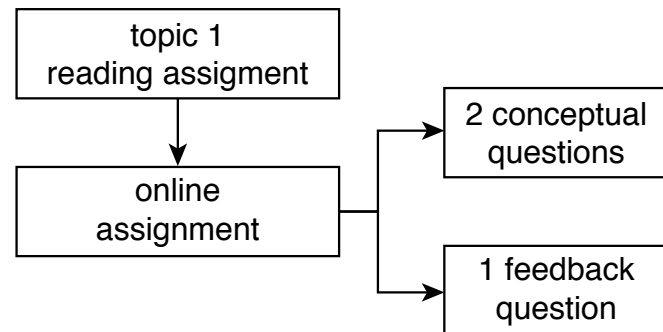
Getting students to read

JiTT workflow



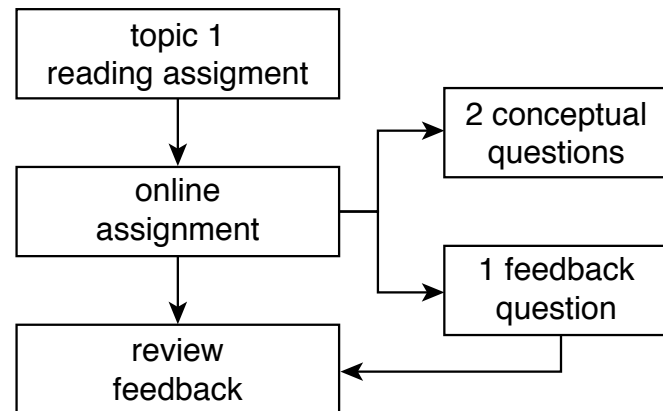
Getting students to read

JiTT workflow



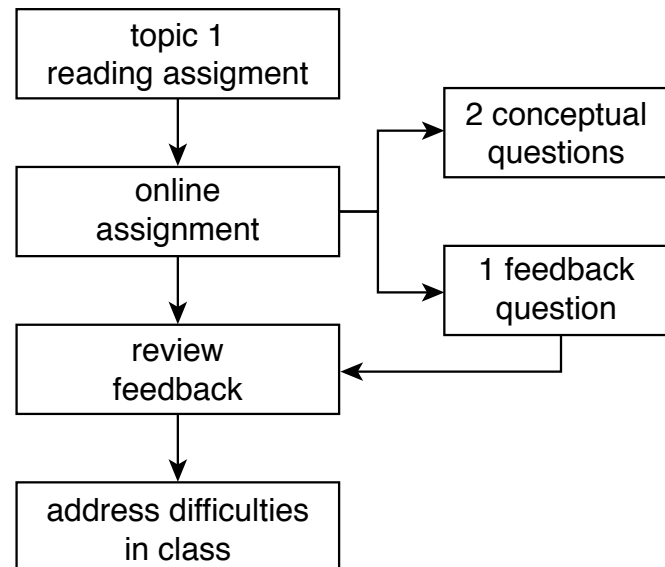
Getting students to read

JiTT workflow



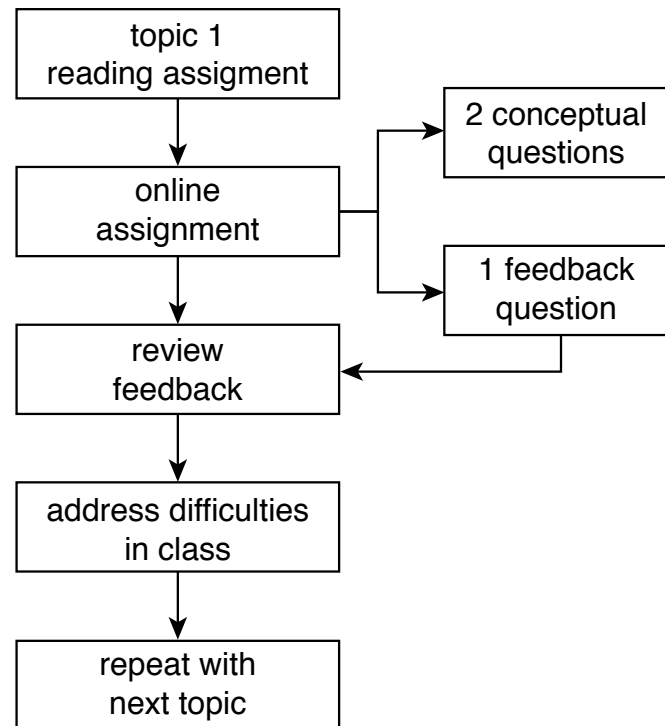
Getting students to read

JiTT workflow



Getting students to read

JiTT workflow

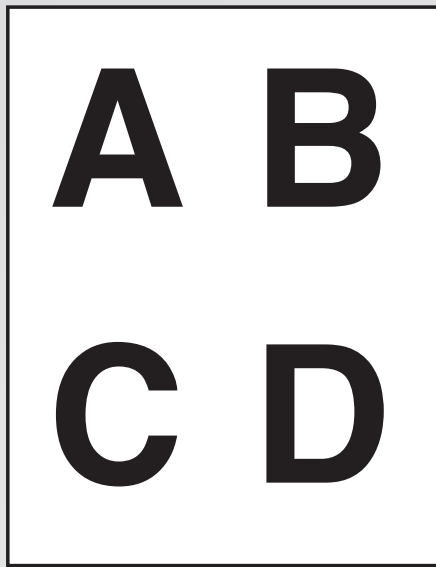


Frequently Asked Questions

“Do I need clickers?”

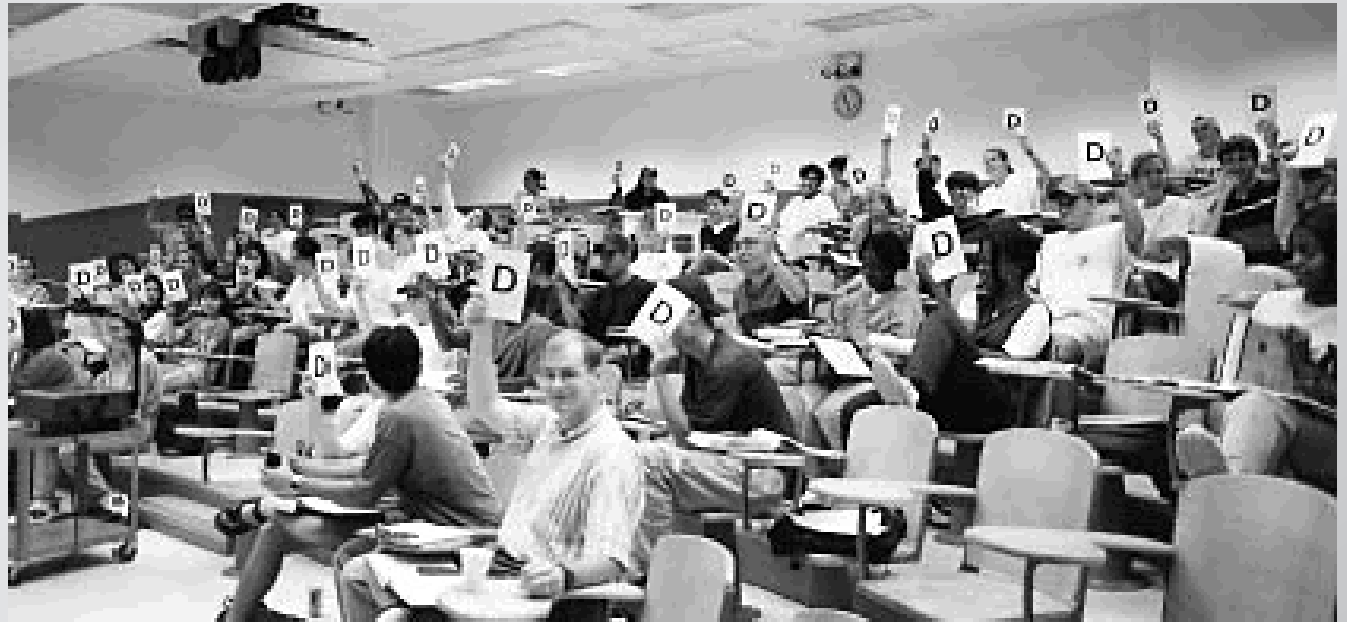
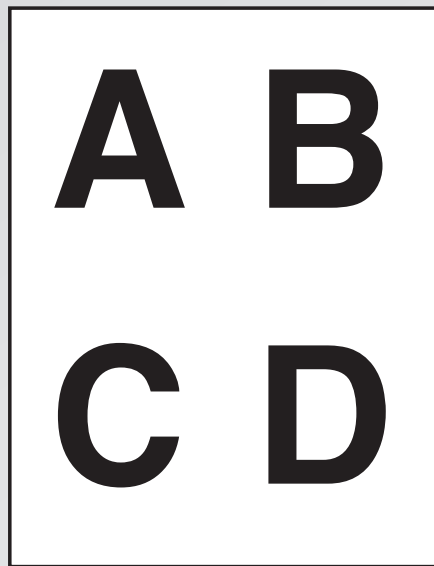
Clickers necessary?

Flashcards: simple and effective



Clickers necessary?

Flashcards: simple and effective



Meltzer and Mannivanan, South Eastern Louisiana University

Clickers necessary?

circumference

Clickers necessary?

circumference

of a circle of radius R is $2\pi R$

Clickers necessary?

Imagine a rope that fits snugly along the equator.



Clickers necessary?

Imagine a rope that fits snugly along the equator.

Suppose the rope is cut and 1 m of rope is inserted between the cut ends. If the rope were to maintain a circular shape, how far off the surface of the Earth would it float?



1. the width of a few atoms
2. the width of a few hairs
3. about 0.15 m
4. exactly 1 m
5. more than 1 m



Clickers necessary?

You all got fired up!

Clickers necessary?

You all got fired up!

(WITHOUT CLICKERS!)

Clickers necessary?

Imagine a rope that fits snugly along the equator.

Suppose the rope is cut and 1 m of rope is inserted between the cut ends. If the rope were to maintain a circular shape, how far off the surface of the Earth would it float?



1. the width of a few atoms
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Clickers necessary?

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1. the width of a few atoms
2. the width of a few hairs
3. about 0.15 m ✓
4. exactly 1 m
5. more than 1 m



Clickers necessary?

circumference at the equator:

$$2\pi R_E$$

Clickers necessary?

circumference at the equator:

$$2\pi R_E$$

new circumference:

$$2\pi R_E + 1 \text{ m}$$

Clickers necessary?

circumference at the equator:

$$2\pi R_E$$

new circumference:

$$2\pi R_E + 1 \text{ m}$$

radius of circle with new circumference:

$$2\pi R = 2\pi R_E + 1 \text{ m}, \quad \text{and so} \quad R = R_E + \frac{1 \text{ m}}{2\pi}.$$

Clickers necessary?

It's not the technology, but the pedagogy!

Clickers necessary?

It's not the technology, but the pedagogy!

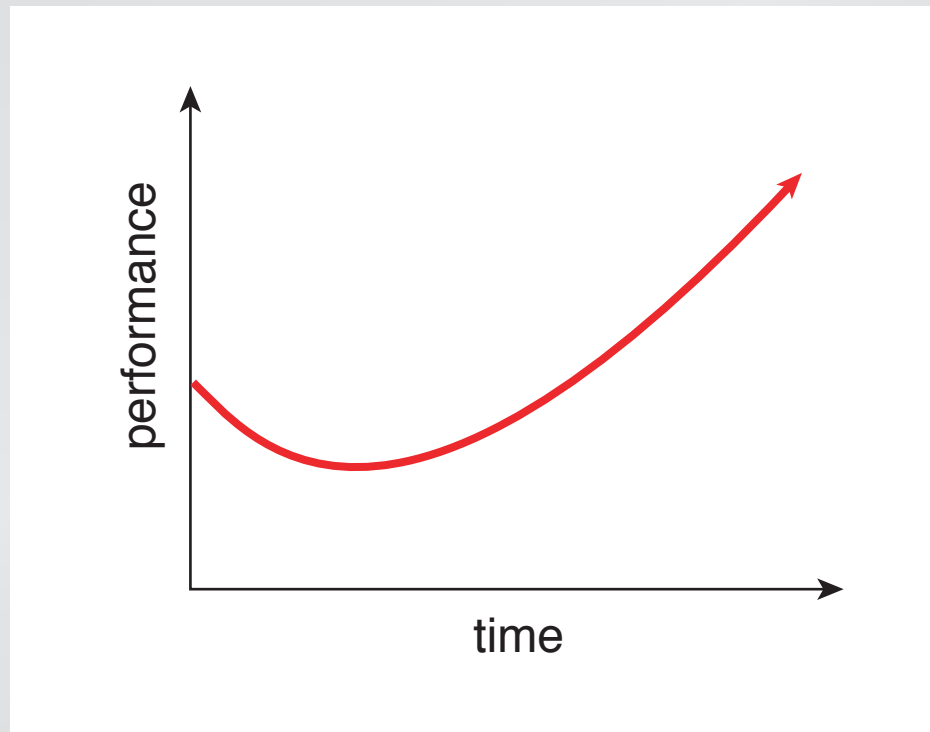
(but clickers do offer advantages)

Frequently Asked Questions

*“How do I deal with students who resist
this new approach to studying?”*

Student resistance

After changing, things might get *worse* before they get better!



Student resistance

Written on Wednesday Feb 16, two weeks into the course:

Subject: concerns

Professor Mazur,

Here are a few concerns. I speak for many of my classmates.

1) You are giving us WAY too much work. After spending multiple hours on the problem set, and not being able to figure out many of the questions, I now see that we have an additional 6 or 7 pages or homework in the workbook. I just spent 4 hours on the lab, and I am not confident on almost half of the questions. This is more work than I have had all semester in all of my other classes combined.

2) If you are going to give us this much work, I would suggest re-structuring the lectures. I find the readings very difficult to understand. I am not a bad student (I got a solid A in physics 1a), but it is very difficult to internalize the readings. You should spend most of the lecture going over, point by point, the readings in their entirety. While the PRS clickers are fun, they do not help me understand the complex material.

I am extremely flustered by the incredibly large amount of work, and my inability to understand it, and I am strongly considering dropping the course.

Student resistance

Written on Monday May 23, just after the final exam:

Subject: Thanks!

Professor Mazur,


First of all I want to thank you for a great semester. You are an excellent professor, and it is clear that you truly care about each and every student.

The exam went well today. I'm not sure to what extent you will curve the final grades (if at all), but it looks like I may be right around the cutoff point between an A and an A-. I studied as hard as I could and I'm keeping my fingers crossed about the A, but no matter what happens with my grade you should know that you are one of the best professors that I have ever had at Harvard.

Thanks again!

Student resistance

Hello Prof. Mayer,
I wanted to hand you this card as
a token of my deep appreciation of
how you have helped me throughout
the semester. You are truly
an inspiring and have
changed how I look at
"learning". I also wanted
to thank you for
how understanding
you were of all
my circumstances.
You really made a difference
in my life. So THANKS
Thank you!
Love, Best.

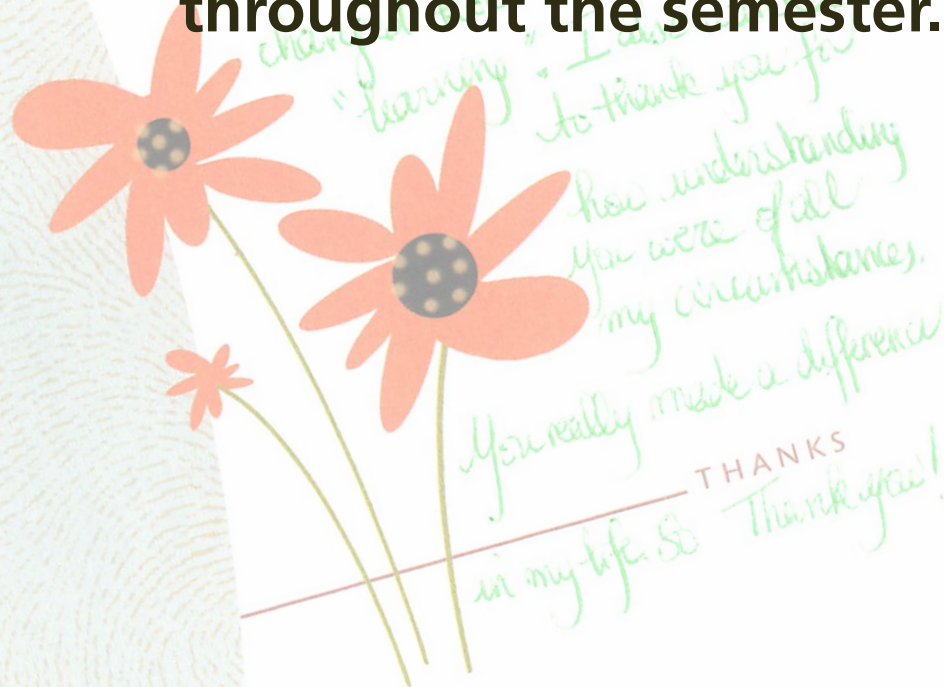


You made a difference.

Student resistance

"I wanted to hand you this card as a token of my deep appreciation of how you have helped me throughout the semester."

You made a difference.



Student resistance

"I wanted to hand you this card as a token of my deep appreciation of how you have helped me throughout the semester. You are truly awe inspiring and have changed how I look at "learning".

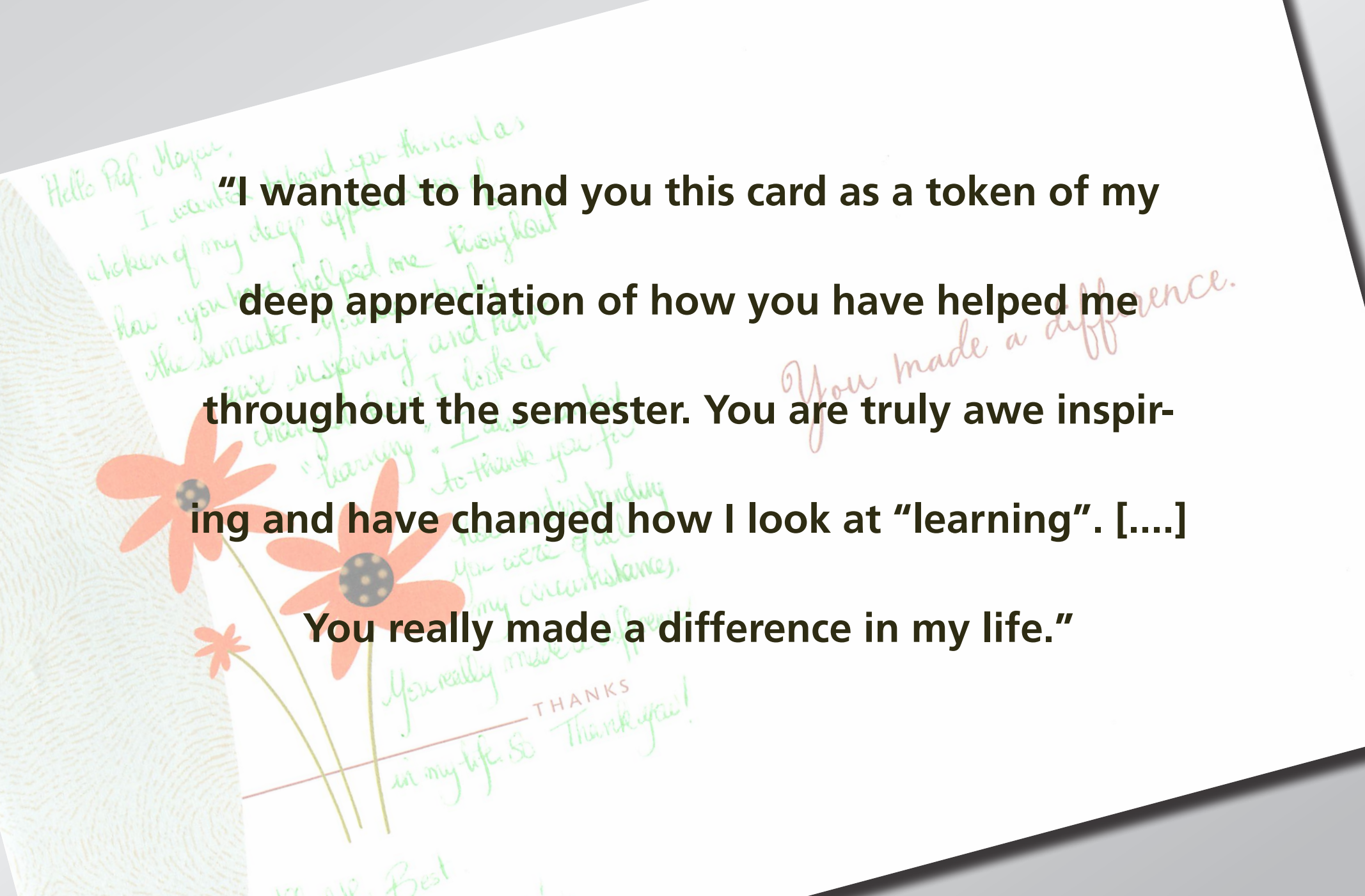
You made a difference.

*THANKS
in my life. So Thank you!*

Best

Student resistance

"I wanted to hand you this card as a token of my deep appreciation of how you have helped me throughout the semester. You are truly awe inspiring and have changed how I look at "learning". [....] You really made a difference in my life."



Student resistance

and don't forget...

Student resistance

and don't forget...

PI leads to better learning and retention!

Getting started

"I still need help getting started..."



Join now!

PeerInstruction.net

Summary



Summary

PI easy to implement (and improves learning gains)



Summary

PI easy to implement (and improves learning gains)

technology facilitates active engagement (but not required)

Funding:

National Science Foundation

for a copy of this presentation:

<http://mazur.harvard.edu>

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eric_mazur