

Teaching with technology in the 21st century



Monash College & Victoria University
Melbourne, Australia, 19 August 2016



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@eric_mazur

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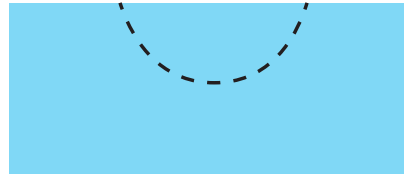
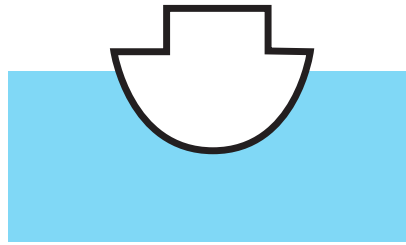
Buoyancy

Archimedes' Principle

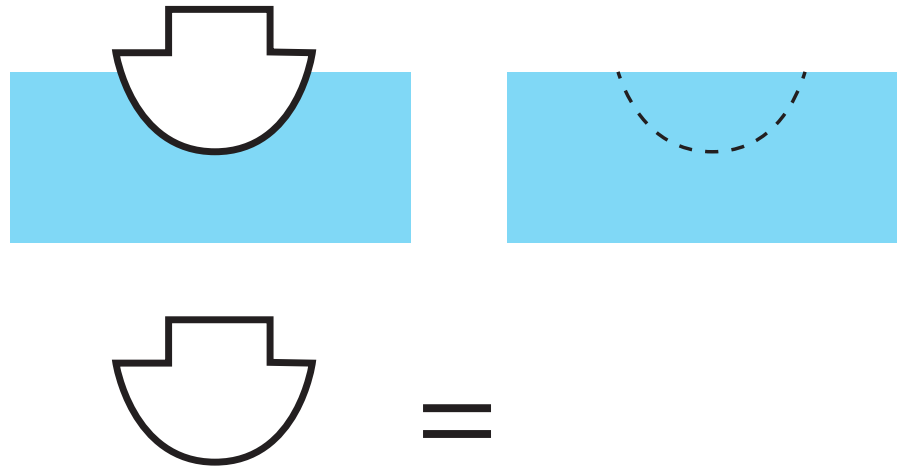
Archimedes' Principle

An object submerged either fully or partially in a fluid experiences an upward buoyant force the magnitude of which is equal to the magnitude of the force of gravity exerted on the fluid displaced by the object. The volume of displaced fluid is equal to the volume of the submerged portion of the object.

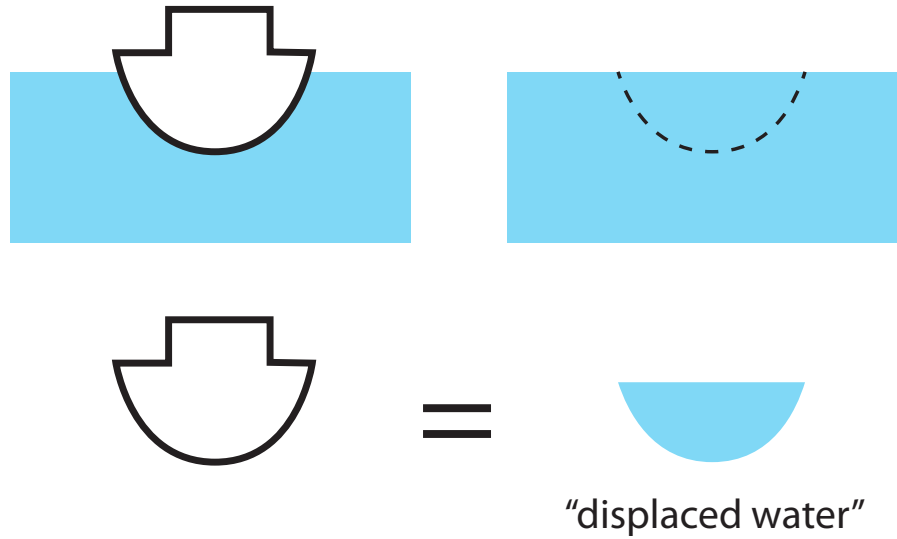
Archimedes' Principle



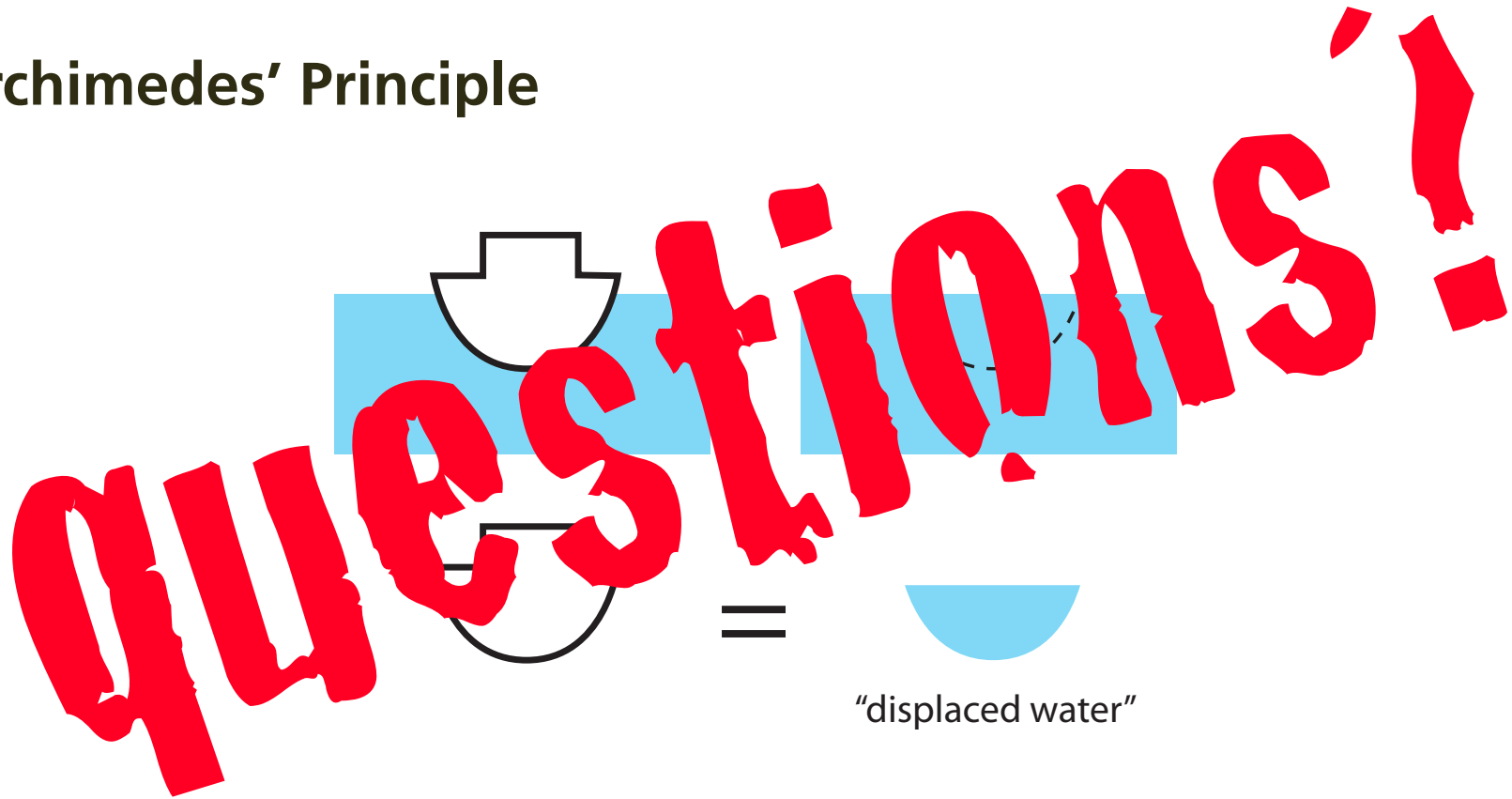
Archimedes' Principle



Archimedes' Principle

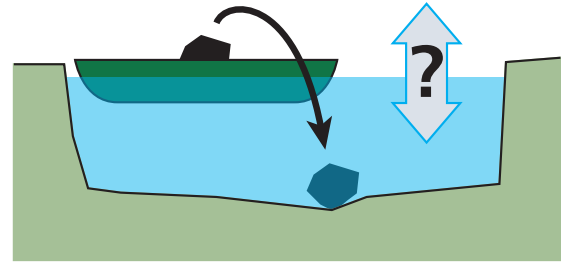


Archimedes' Principle

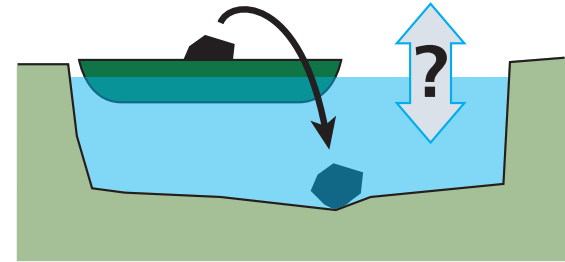


"displaced water"

A boat carrying a large boulder is floating on a small pond. The boulder is thrown overboard and sinks to the bottom of the pond.



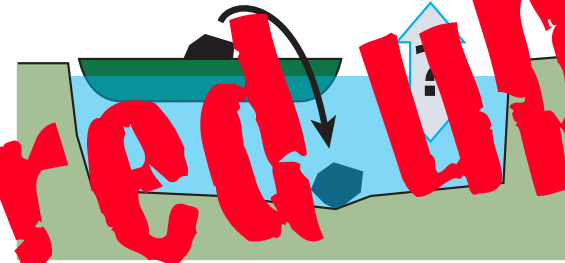
A boat carrying a large boulder is floating on a small pond. The boulder is thrown overboard and sinks to the bottom of the pond.



After the boulder sinks to the bottom of the pond, the level of the water in the pond is

- 1. higher than,**
- 2. the same as,**
- 3. lower than it was when the boulder was in the boat.**

A boat carrying a large boulder is floating on a small pond. The boulder is thrown overboard and sinks to the bottom of the pond.



After the boulder sinks to the bottom of the pond, the level of the water in the pond is

1. higher than,
2. the same as,
3. lower than it was when the boulder was in the boat.

you got all fired up!

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...

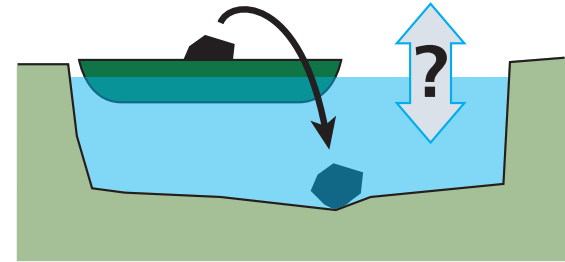
- 1. made a commitment**
- 2. externalized your answer**
- 3. moved from the answer/fact to reasoning**

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**

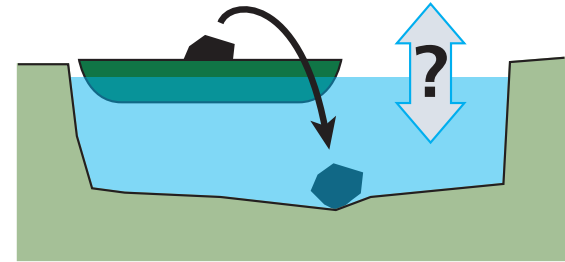
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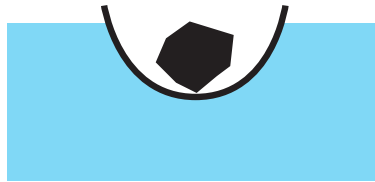


After the boulder sinks to the bottom of the pond, the level of the water in the pond is

1. higher than
2. the same as
3. lower than it was when the boulder was in the boat. ✓

remember: amount of displaced water

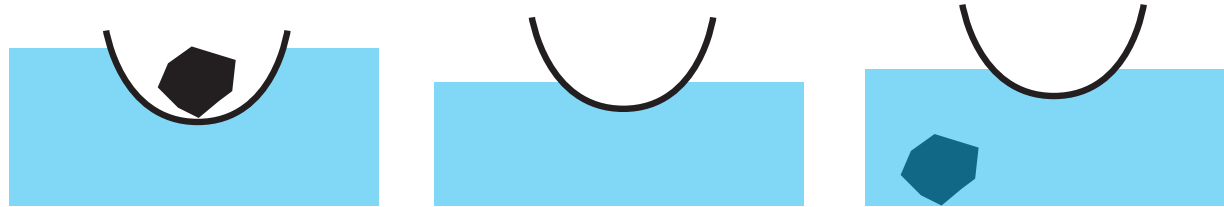
remember: amount of displaced water



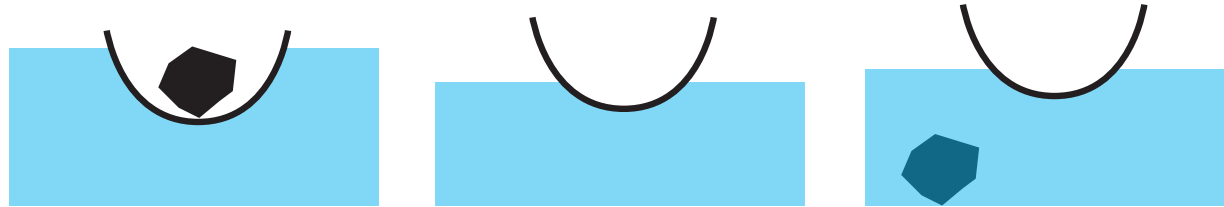
remember: amount of displaced water



remember: amount of displaced water

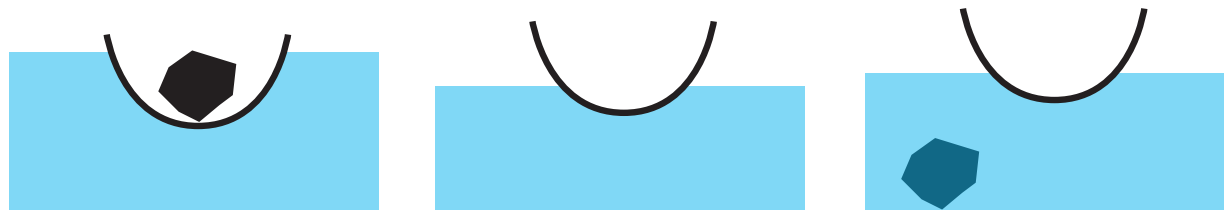


remember: amount of displaced water



displaced
water

remember: amount of displaced water



displaced
water



= weight
of rock



= volume
of rock

remember: amount of displaced water



you won't forget this

displaced
water



= weight
of rock



= volume
of rock

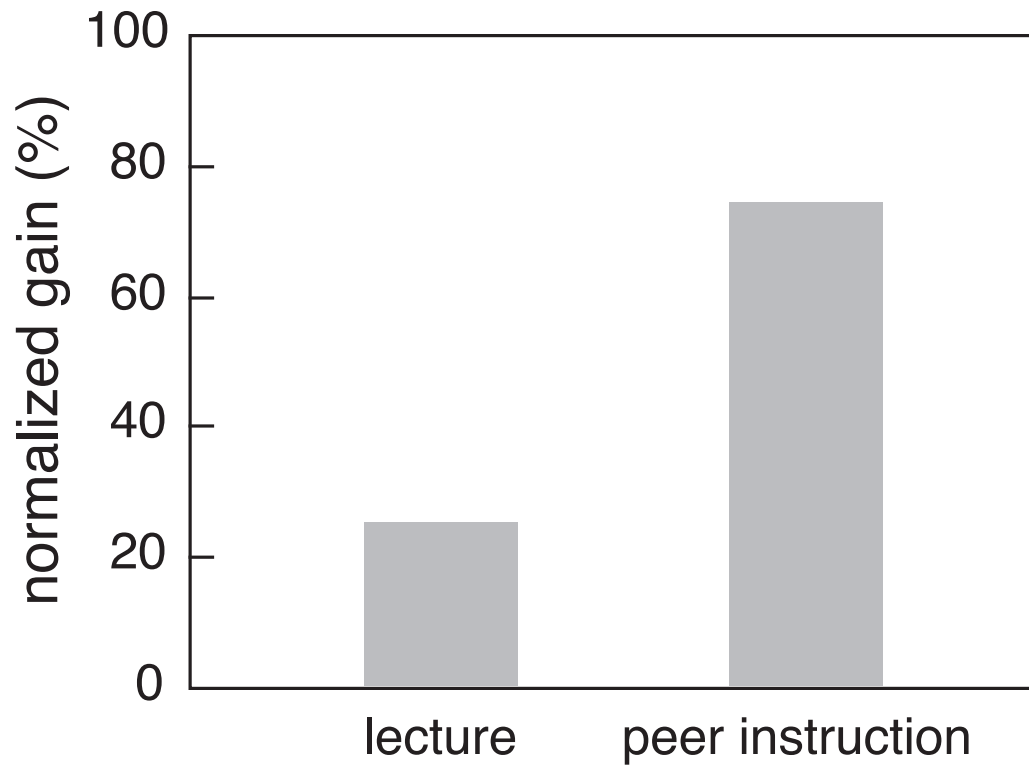
Peer

back to pi

INSTRUCTION

Higher learning gains

INSTRUCTION



Peer

Higher learning gains

Better retention

INSTRUCTION



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

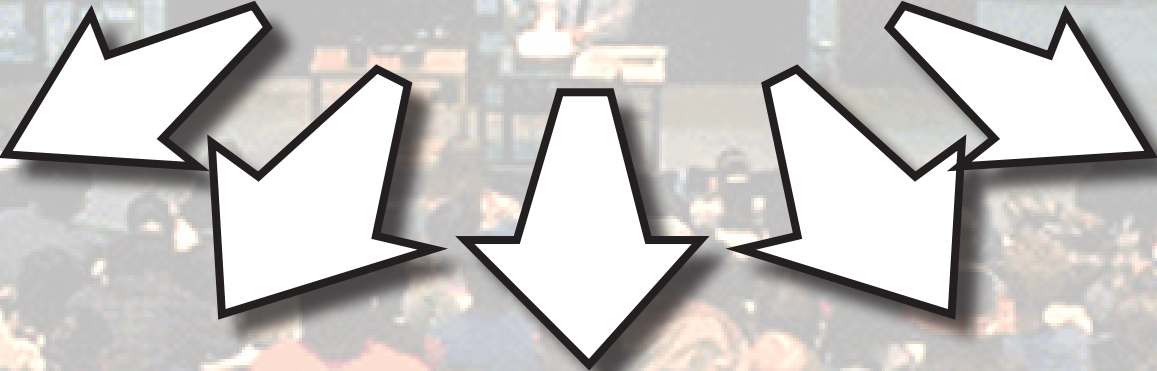


1st exposure



deeper understanding


how to effectively transfer information outside classroom?





but...

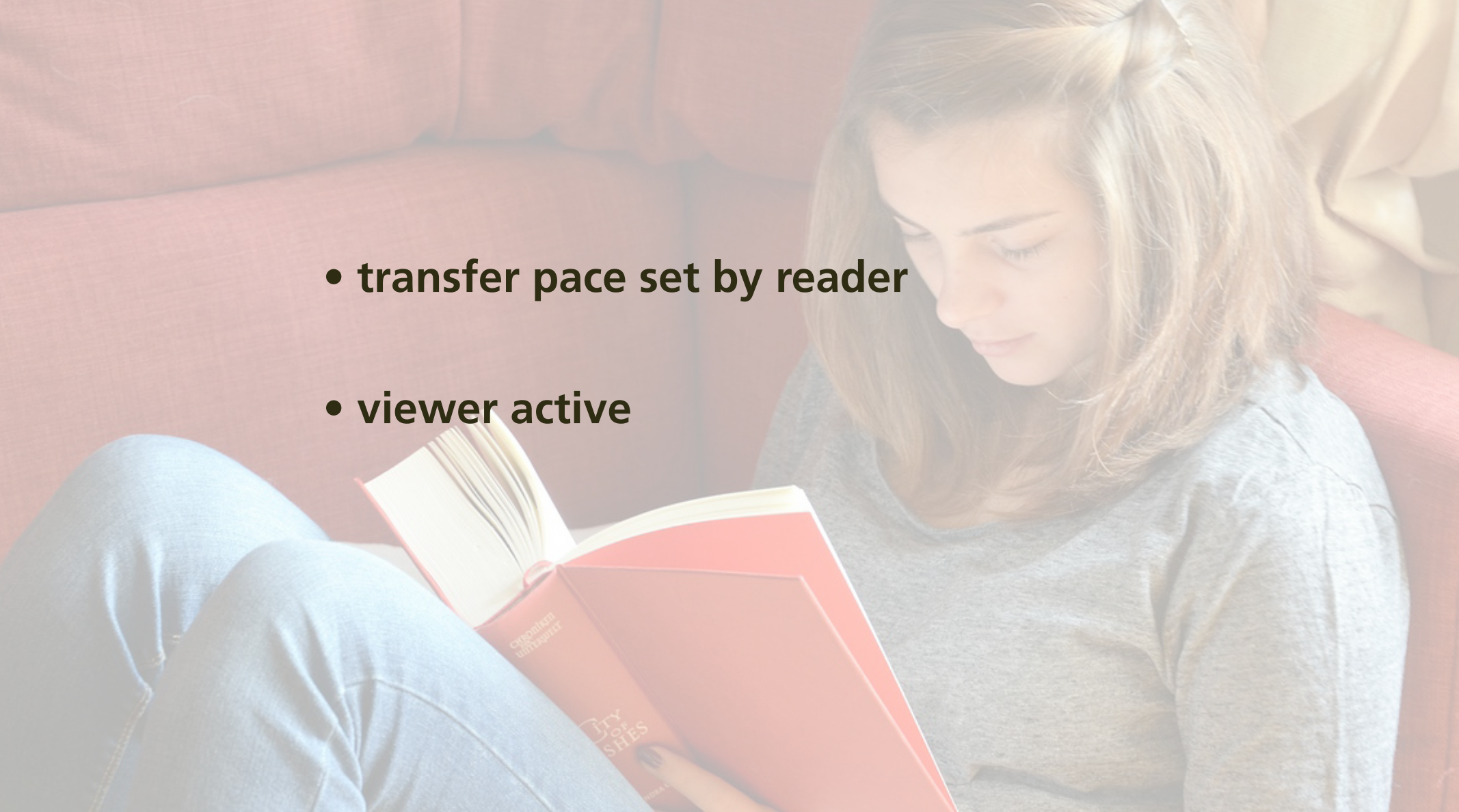


- **transfer pace set by video**
 - **viewer passive**
 - **viewing/attention tanks as time passes**
 - **isolated/individual experience**
- 



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)

An illustration of a classroom with several students sitting at desks. The students are rendered in a semi-transparent, stylized manner with various colors like purple, blue, green, and yellow. They appear to be engaged in a learning activity, with some holding papers or pens. The background is a simple, light-colored wall.

Solution

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

Perusal1

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 sliding on a horizontal wooden surface. It starts with a certain initial velocity, 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 4.2 Low-friction track and carts used in the experiments described in this chapter.



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

social learning platform

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



4.1 Friction

log in through social network



When a block slides across a surface, it 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 experience: a hockey puck slides easily on ice. The velocity of a wheel on different surfaces. The slower the resistance to motion that one surface offers when moving over another. The distance covered by the velocity-velocity decrease as the block slides 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.

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 holes through which pressurized air flows. This is a cushion on which a conventional cart, with friction between the wheels and the track, is eliminated. Alternatively, one can use air friction bearings on an ordinary track. The low-friction carts you may have encountered in physics tracks and for the track shown in Figure 4.2, the friction is so small that it can be ignored during an experiment. For example, if the track in Figure 4.2 is horizontal, carts move along its length without slowing down appreciably. In other words:

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Figure 4.1 shows how the velocity of a wooden block decreases on three different surfaces. The slowing down is due to *friction*—the 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.

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

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see who is online

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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 time interval between a shove or its equivalent and the block coming to rest can vary from a few seconds to a few minutes. If the surface is particularly 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 4.2 Low-friction track and carts used in the experiments described in this chapter.



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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, 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.



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?

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

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Figure 4.1 shows how the velocity of a wooden block decreases on three different surfaces. The rougher the surface, the more quickly the velocity decreases. In the 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

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Figure 4.1 shows how the velocity of a block decreases on three different surfaces. The higher 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.

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



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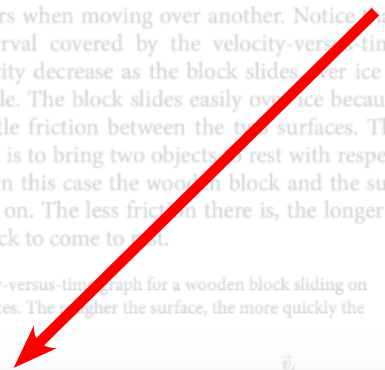
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...opens chat window



Enter your comment or question and press Enter

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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.



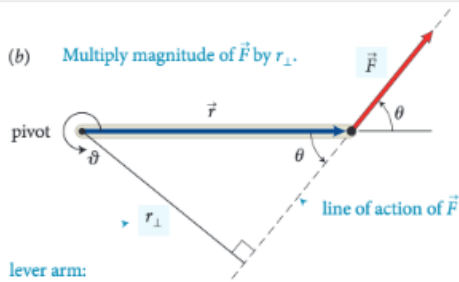
4.1 (a) Are the accelerations of the motions shown in Figure 4.1 constant? (b) For which surface is the acceleration largest in magnitude?



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



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



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

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

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

In the situations depicted in Figures 12.4 and 12.5 we used the pivot to calculate the lever arm distances. This is a natural choice because that is the point about which the object under consideration is free to rotate. However, torques also play a role for stationary objects that are suspended or supported at several different points and that are not free

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}^c 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}^c 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:

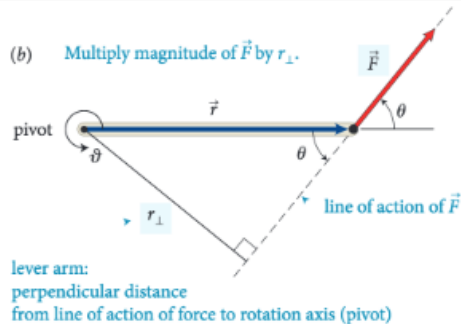
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12.2 In the situation depicted in Figure 12.2a, you must

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



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

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SB

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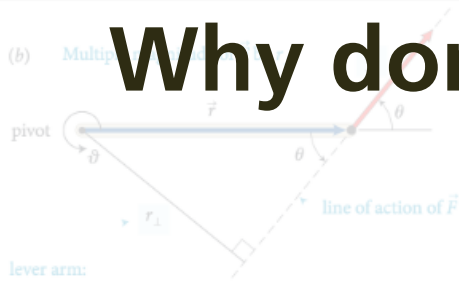
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3. enter code BLC16



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

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reference point. The lever arm distance of force \vec{F}_1 to this left end of the rod. The lever arm distance of force \vec{F}_2 to this 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 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 . The net torque 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. ✓

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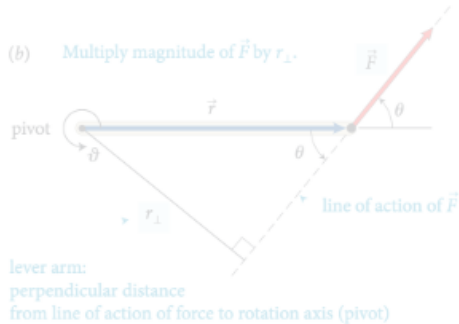
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I don't understand the definition of torque. The magnitude of the torque tells you anything about direction? Aren't magnitude and lever arm distance both scalar quantities? It seems like we would need to know some sort of direction to calculate torque.

I think you may be confused. Torque is a vector quantity. When you calculate the magnitude of the torque, you can attach a sign to the torque based on the defined parameters of the system. In the following paragraph, they start to explain how to choose this direction.

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how to get students to participate?

Oct 20 12:09 am

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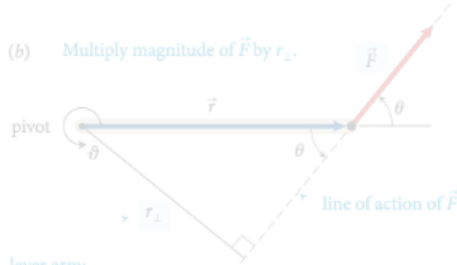
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perpendicular distance
from line of action of force

use combination of

intrinsic and extrinsic motivation drivers

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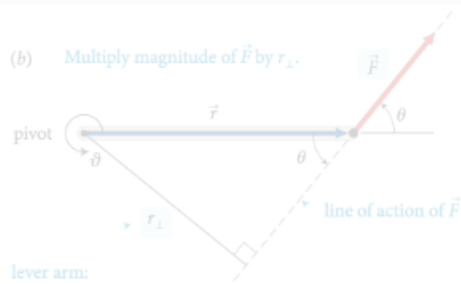
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rubric-based assessment

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



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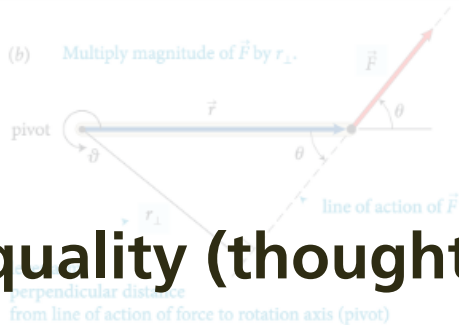
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rubric-based assessment

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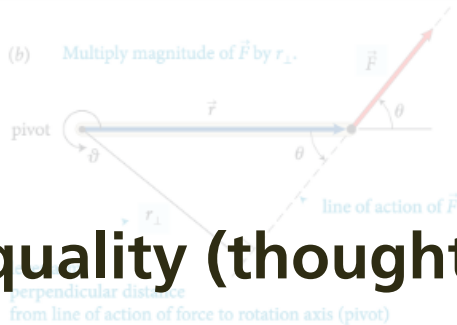
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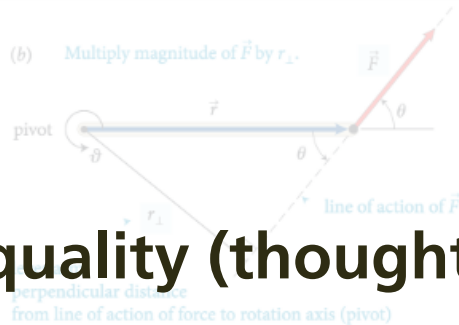
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rubric-based assessment

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Oct 22 8:48 pm

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}_{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 found for the torques about the pivot, and so the sum of the torques about the left end is zero. ✓

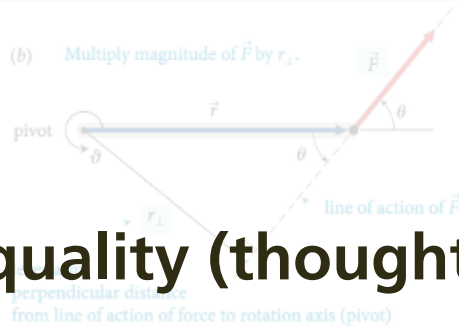
Exercise 12.1 shows that the sum of the torques about the left end of the rod is zero, just like the sum of the torques about the pivot. You can repeat the calculation for the torques about the right end of the rod or any other point, and each time you will find that the sum of the torques is zero. The conclusion 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.

rubric-based assessment

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



- quality (thoughtful reading & interpretation)

- quantity (minimum 10)

- timeliness (before class)

- distribution (not clustered)

The lever arm distances must now be determined relative to the left end of the rod. The lever arm distance of force \vec{F}_1 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}_{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 conclusion 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 for calculating torques. It pays to choose a reference point that eliminates as many forces as possible from 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.

I don't understand how this combination of factors tells you anything about direction? Aren't magnitude and lever arm distance both scalar quantities, so how do we know some sort of direction? 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. I can 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 Oct 22 8:48 pm

rubric-based assessment

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



• quality (thoughtful reading & interpretation)

• quantity (minimum 10)

• timeliness (not for class)

• distribution (not clustered)

OVER 20,000 annotations!

How do you understand how this combination of factors affects you anything about direction? Aren't magnitude and lever arm distance both scalar quantities? It seems like we would know some sort of direction is called torque.

I think you may be able to figure out the direction separately. So when you multiply the distance, you get a sign to indicate the direction of the torque. In this case, you can explain how to choose the sign of the torque.

This is a vector quantity. To find the magnitude of this, we use the equation for torque. The equation for torque is $\tau = rF \sin(\theta)$, with r being the level arm distance and F being the magnitude of the force. We know that force is a vector from previous

The sum of the torques must now be zero. If I choose the pivot at the left end of the rod, the torque caused by the force F_1 at the right end of the rod is $\tau_1 = r_1 F_1$. If I choose the pivot at the right end of the rod, the torque caused by the force F_2 at the left end of the rod is $\tau_2 = r_2 F_2$. Because the rod is in equilibrium, the sum of the torques about the pivot is equal to zero. Taking into account the sign of the torques, we find that the sum of the torques about the left end of the rod is $r_1(F_1 + F_2) - (r_1 + r_2)F_2 = 0$. This is the same as $r_1 F_1 = (r_1 + r_2)F_2$. The sum of the torques about the right end of the rod is $(r_1 + r_2)F_1 - r_2(F_1 + F_2) = 0$. This is the same as $r_2 F_2 = (r_1 + r_2)F_1$. The sum of the torques about the pivot is zero.

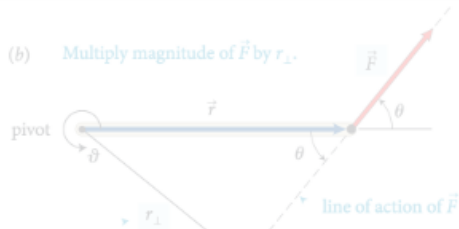
Exercise 12 shows that the sum of the torques about the left end of the rod is zero. Like the sum of the forces, the sum of the torques about the right end of the rod is also zero. We can find the sum of the torques about any point, and the sum will be zero. For a stationary object, the sum of the torques is zero.

For a stationary object we can choose any reference point for calculating torques. It pays to choose a reference point that eliminates the most forces from 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, the sum of the torques about the left end of the rod is zero.

rubric-based assessment

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



- quality (thoughtful reading & interpretation)

how do you process all of that??

- quantity (minimum 10)

- timeliness (before class)

- distribution (not clustered)

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 first part of the question, 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 $\tau = \vec{r} \times \vec{F}$, with \vec{r} being the level arm distance and \vec{F} being force. We know that force is a vector vector from previous

Oct 22 8:48 pm

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}_{pr} to the left end of the rod 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 . The torques about the left end of the rod are $\tau_1 = r_1 F_{pr}$ and $\tau_2 = -r_2 F_2$. The sum of the torques 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.

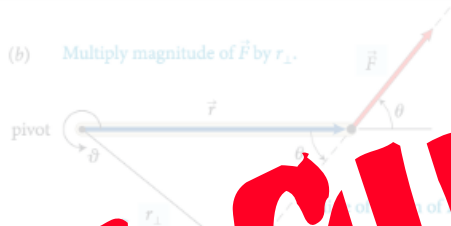
For a stationary object we can choose any reference point we like to calculate torques. It pays to choose a reference point that eliminates the calculation. As you have seen, we do not need to consider any force that is exerted at the reference point. So, by putting the reference point at the point of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



12.2 In the situation depicted in Figure 12.2a, we must

rubric-based assessment

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



fully automated

how do you process all of that??

assessment

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 need to know some sort of direction to calculate torque.

• **timeliness**

I think you may be able to calculate the magnitude of the torque and direction separately. So, after multiplying the magnitude of the force by the distance, you can attach a sign to the result based on the definition of the parameters of the system. In other words, you need to explain how to choose this direction.

• **discussion (not clustered)**

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

reference point

The diagram shows a rod pivoted at its left end. A force vector \vec{F} is applied to the rod at a distance r from the pivot. The force is perpendicular to the lever arm r_{\perp} . The angle between the force and the rod is θ .

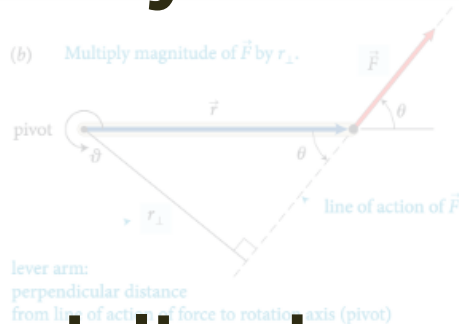
Exercise 12.2 shows that the sum of the torques about the rod of a stationary object is zero. You can see this by calculating the sum of the torques about any point. The sum of the torques is not zero about any point other than the pivot. In general we can say:

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 eliminates some of 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, a must

fully automated assessment



- specialized machine learning algorithm

- assesses intellectual content

- exceeds intercoder reliability

? I don't understand how the direction of the force 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 want to consider direction separately. So, after multiplying the 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

Oct 22 8:48 pm

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 F_1 and F_2 . Taking torques about the left end of the rod, we find $r_1(F_1 + F_2) - (r_1 + r_2)F_2 = r_1F_1 - r_2F_2$. 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. The sum of 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:

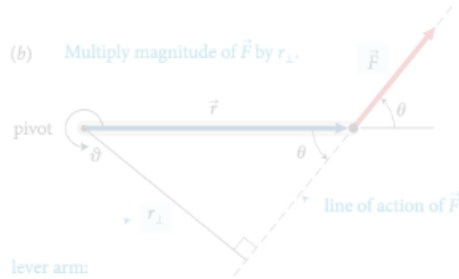
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For a stationary object we can choose any reference point we like to calculate torques. It pays to choose a reference point that simplifies the calculation. As you have seen, we do not need to consider any force that is exerted at the reference point.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

(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

reference point.

\vec{F}_1

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 . 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. ✓

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connect pre-class and in-class activities

Oct 20 12:09 am

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 12:38 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 22 8:48 pm

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

confusion report

Confusion report for Chapter 24

right hand rule (11 questions)

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

direction magnetic field (8 questions)

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

earth magnetic field (6 questions)

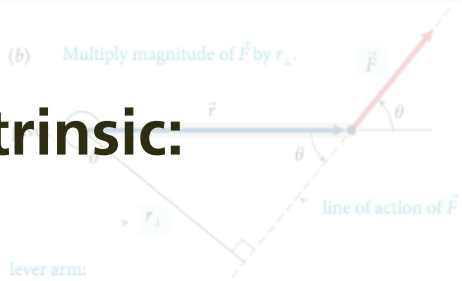
- CP Does that mean that the compass will be distracted from the Earth's magnetic field and use the magnetic field that the current of the wire gives off?

motivating factors

Intrinsic:

- social interaction

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



lever arm:
perpendicular distance
from line of action

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
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. ✓

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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

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motivating factors

Intrinsic:

- social interaction

- tie-in to in-class activity

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



lever arm:
perpendicular distance
from line of action

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

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

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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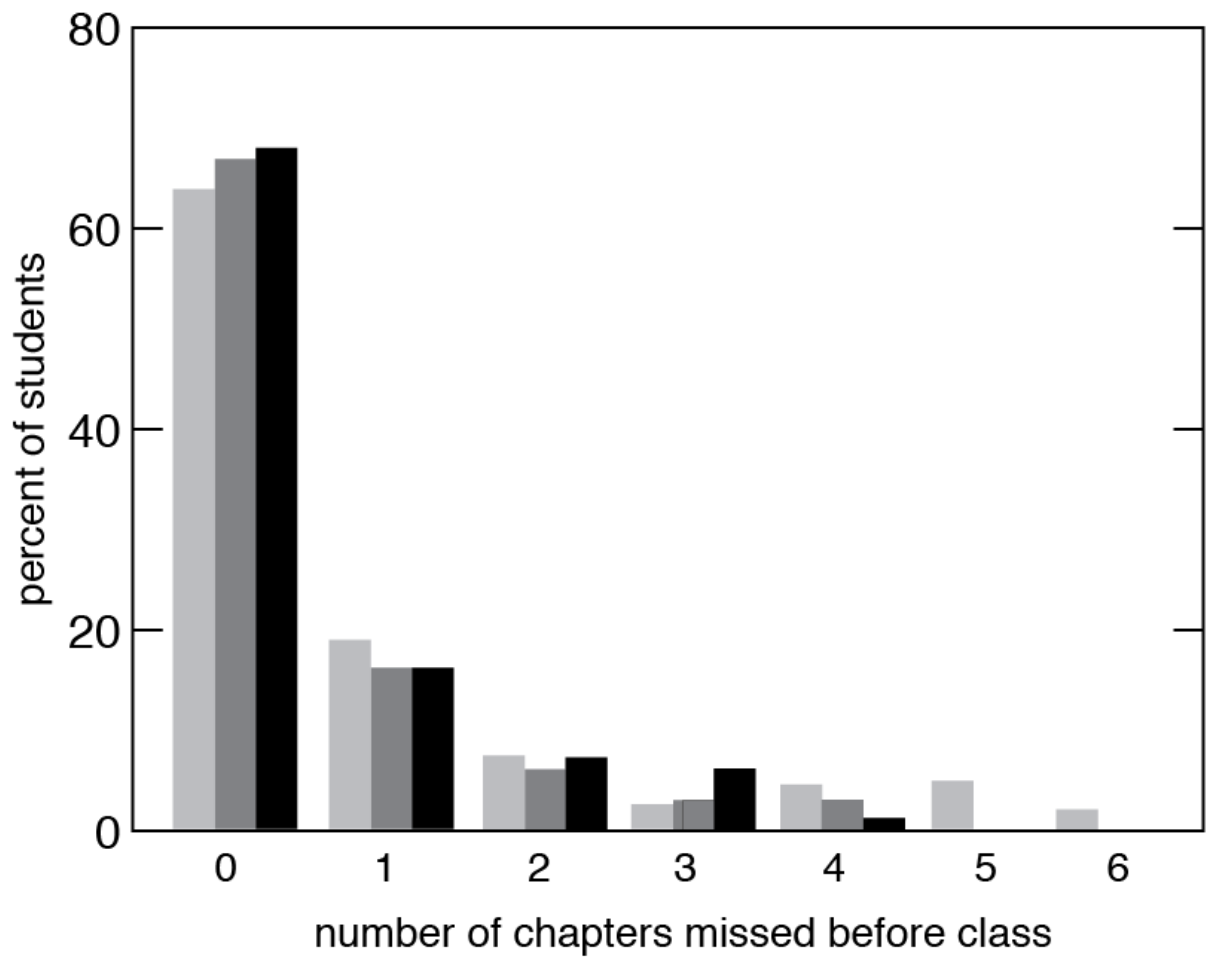
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13.2 In the situation depicted in Figure 13.2a, we must

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

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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



I don't understand how factors tells you any lever arm distance both s know some sort of direct

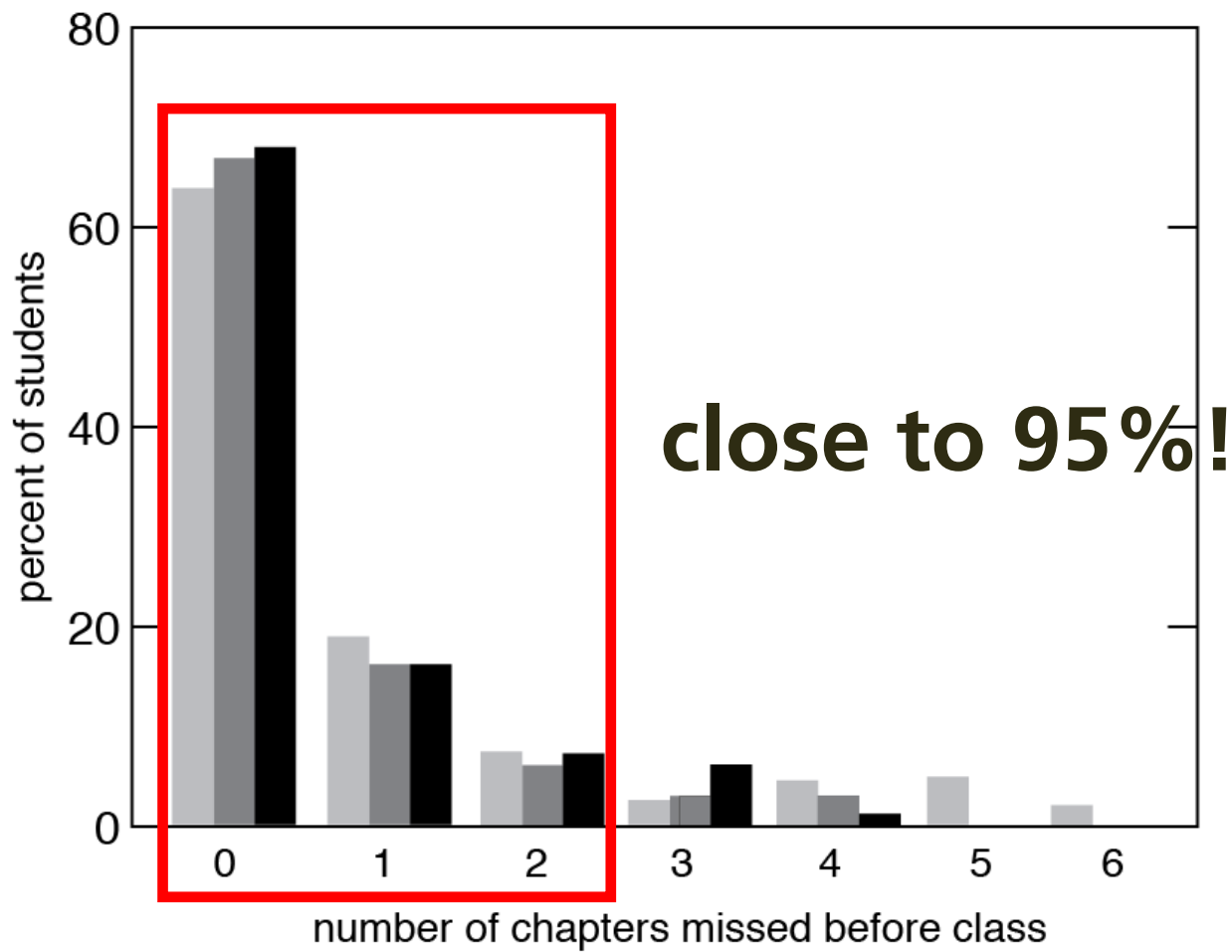
I think you may be a direction separately, distance, you can attach parameters of the system explain how to choose th

This is a great quest 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

line equation:

13.2 In the situation depicted in Figure 13.2a, we must



I don't understand how factors tells you any lever arm distance both s know some sort of direct

I think you may be a direction separately, distance, you can attach parameters of the system explain how to choose th

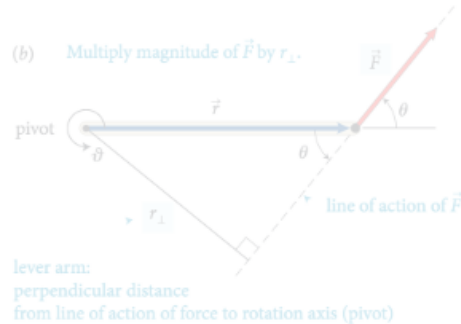
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equation for torque is $\tau = r \times F$, with r being the level arm distance and F being force. We know that force is a vector vector from previous

line calculation:

13.2 In the situation depicted in Figure 13.2a, the mass

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



acted on the rod. 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

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 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, we must

every student prepared for every class

Oct 20 12:09 am

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 12:38 am

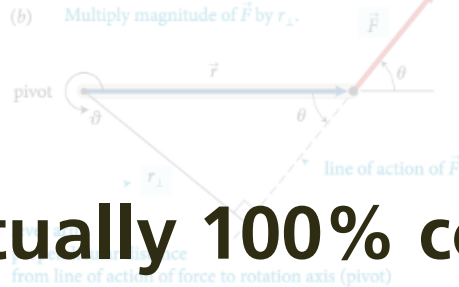
I think you may be able to think about the direction separately. So, after multiplying this magnitude and distance, you can attach a sign to the torque based on the defined parameters of the system. In the following paragraph, they start to explain how to choose this direction.

Oct 22 8:48 pm

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

Benefits

- virtually 100% completion of assignments
- improved use of class time



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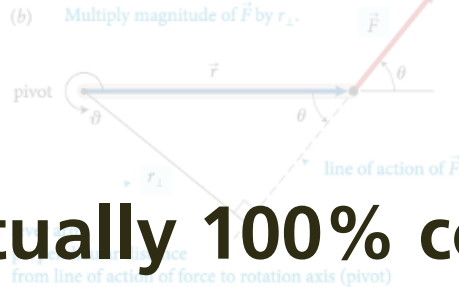
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