

Getting every student prepared for every class



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Webinar
2 March 2017

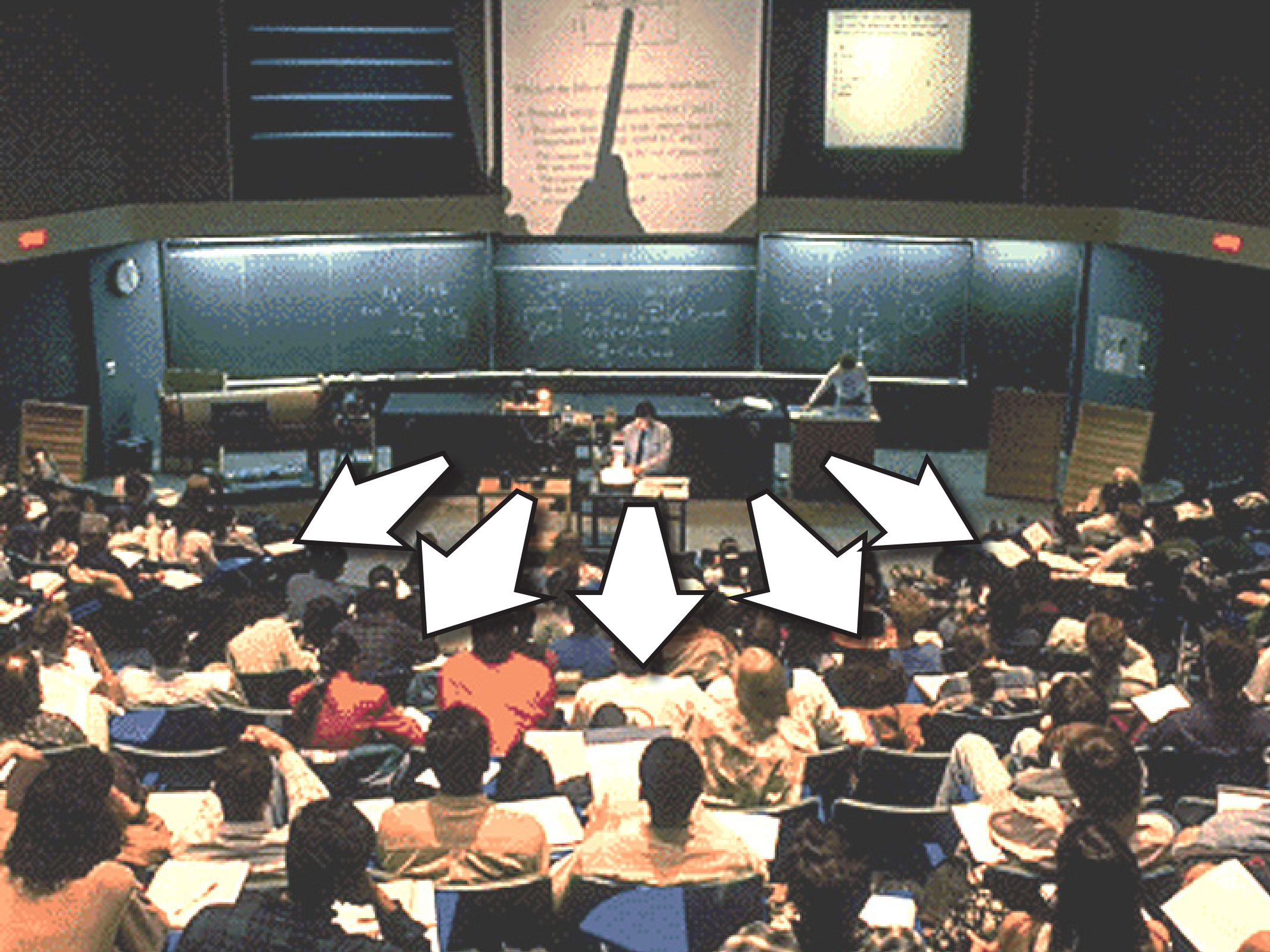
Getting every student prepared for every class



@eric_mazur

Webinar
2 March 2017







CLASS

1st exposure



ROOM

deeper understanding



1st exposure



deeper understanding



1st exposure



deeper understanding



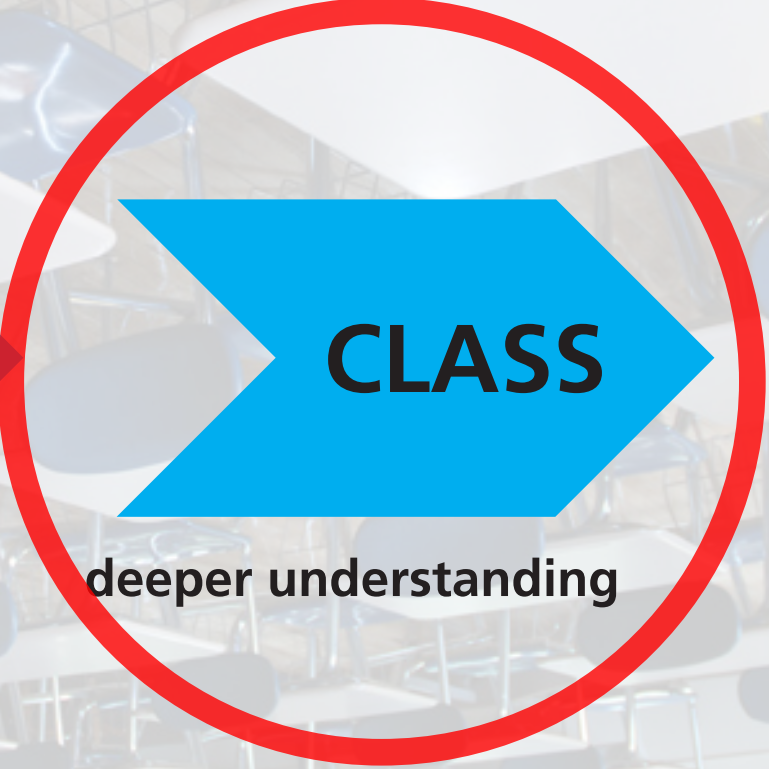
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deeper understanding



1st exposure



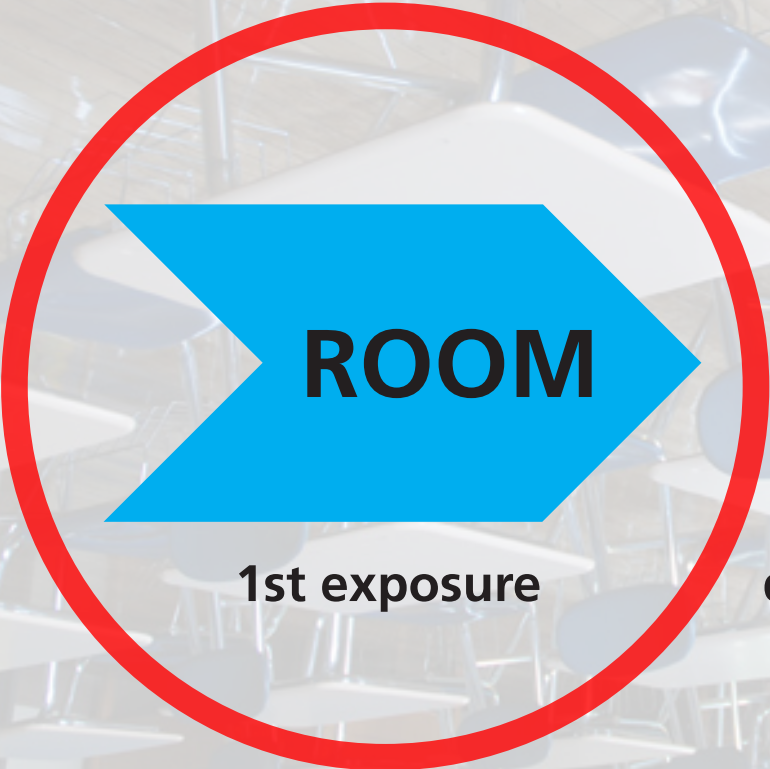
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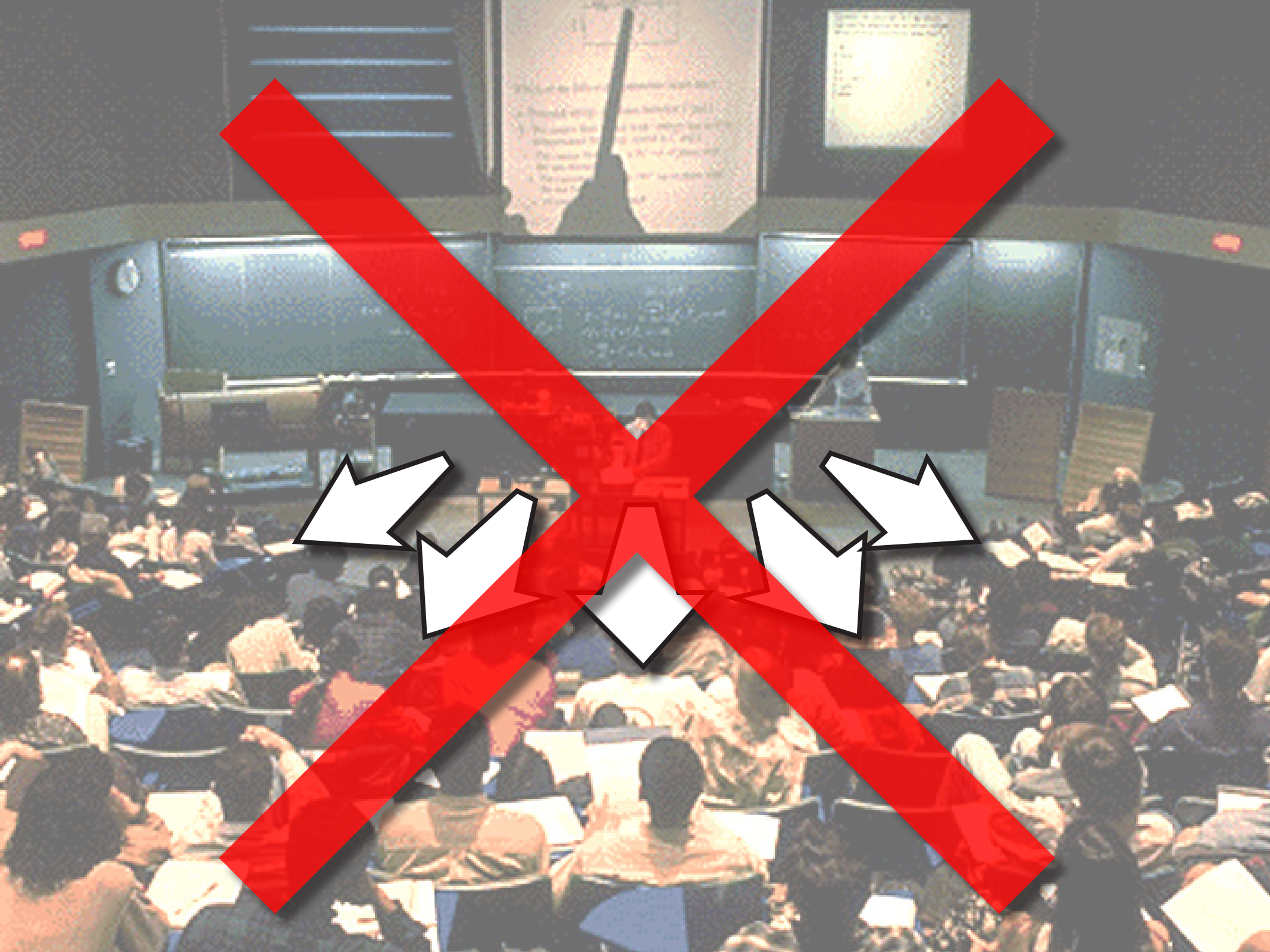
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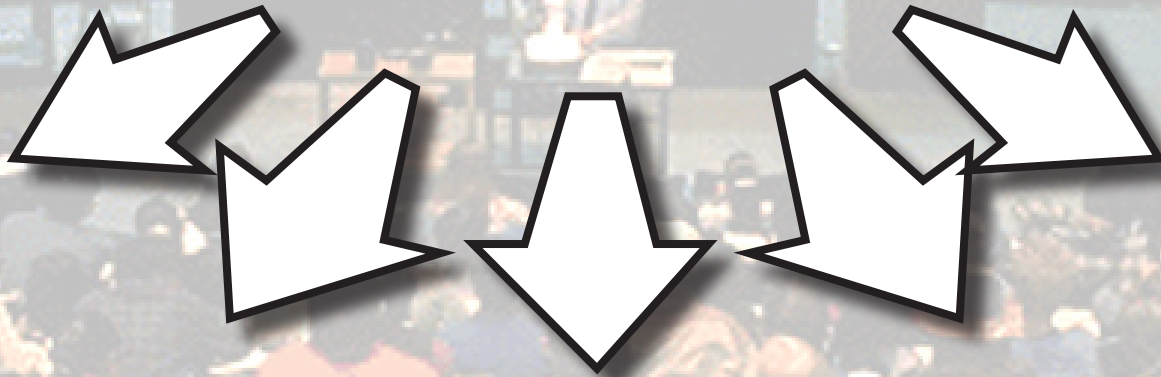
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deeper understanding



how to effectively transfer information outside classroom?





but...



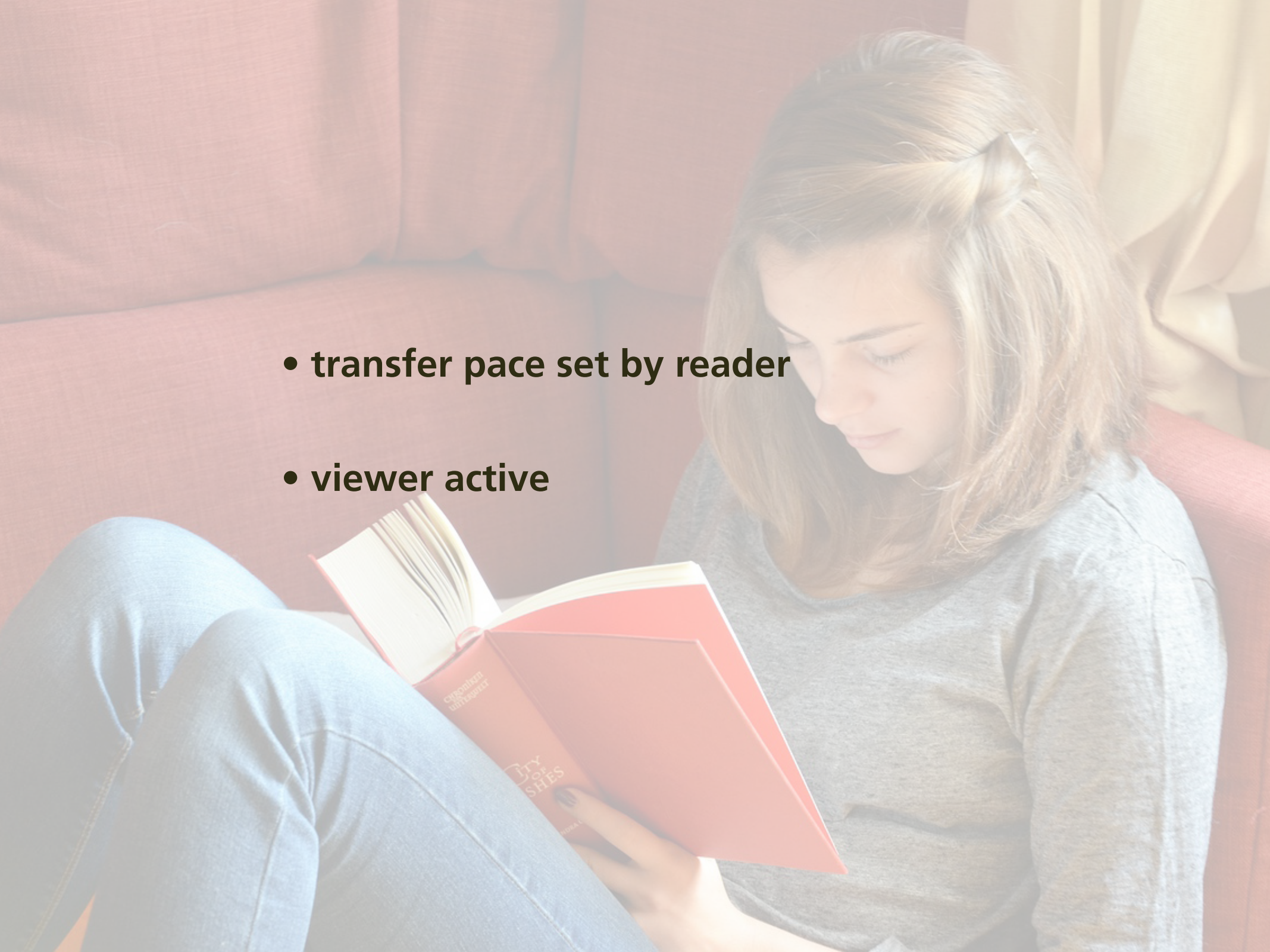
- **transfer pace set by video**
- **viewer passive**
- **viewing/attention tanks as time passes**
- **isolated/individual experience**






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)

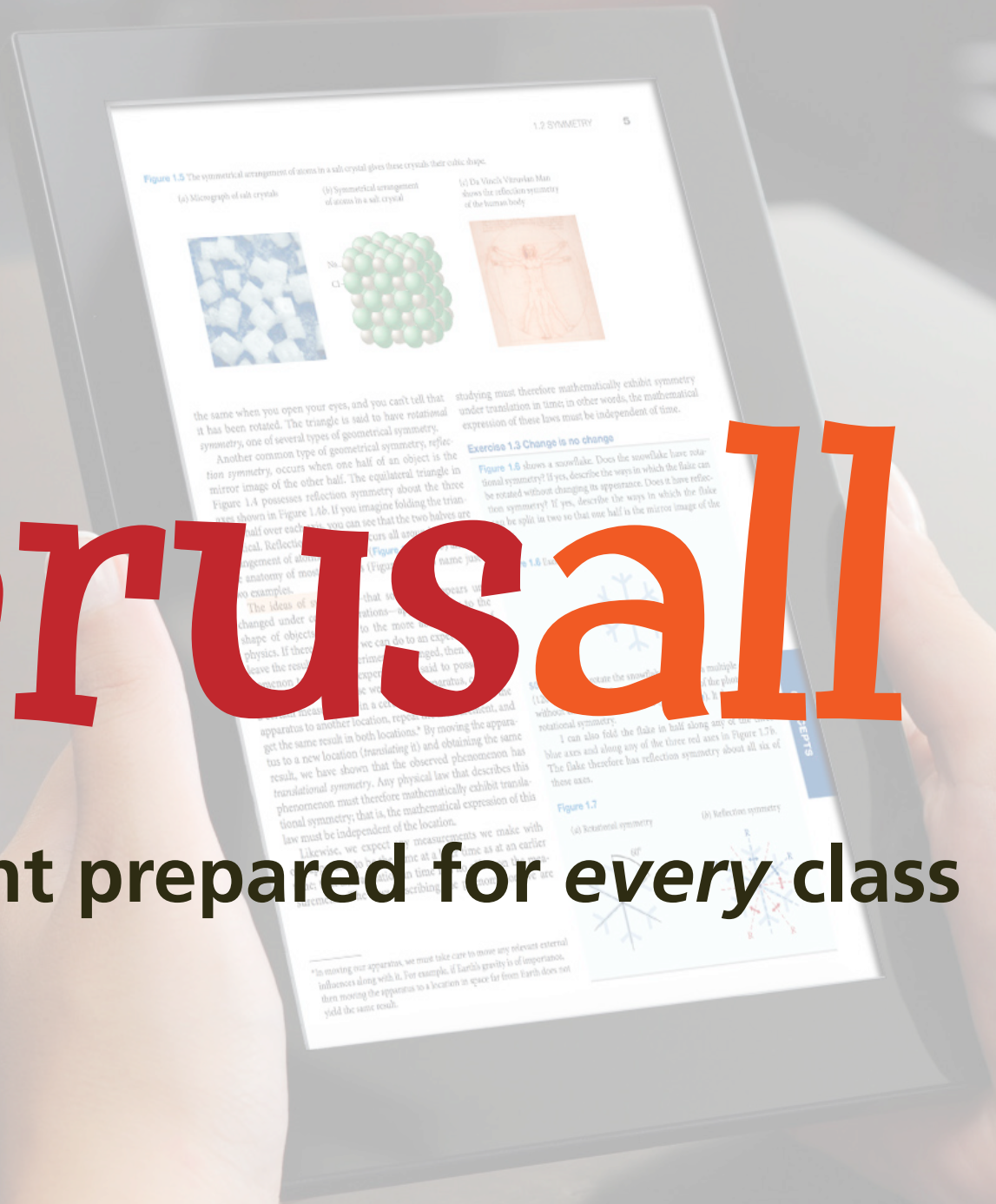


Solution

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

Perusall

every student prepared for every class



76 CHAPTER 4 MOMENTUM

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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 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. This is a familiar 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 an air hockey table. The air is blown through a series of holes in the table, creating a thin layer of air that 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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log in through social network



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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 decreases as the block slides over ice; it hardly decreases at all as the block slides over a smooth surface; and it decreases rapidly as the block slides over a 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.

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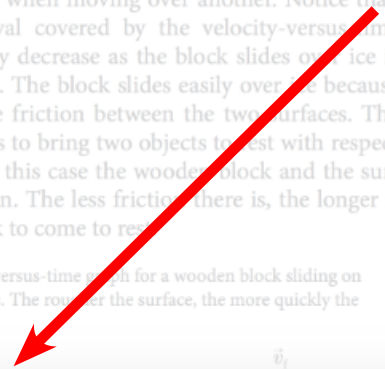
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No friction at all seems impossible. Isn't there always some friction in any real case.

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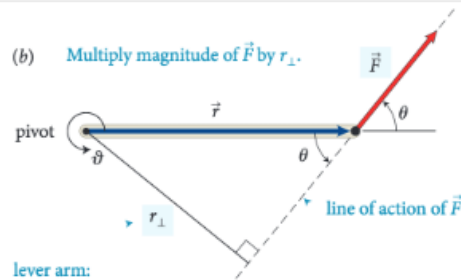
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(b) Multiply magnitude of \vec{F} by r_{\perp} .



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

action of the force and the axis of rotation. So, the torque caused by a force exerted on an object is the product of the magnitude of the force and its lever arm distance. It can be written equivalently as rF_1 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).

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. ✓

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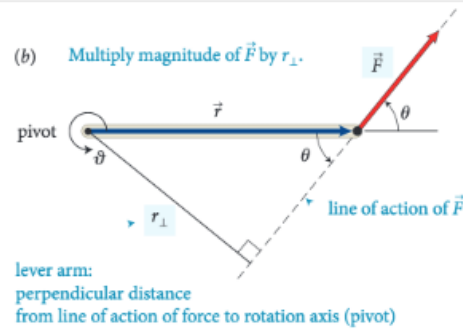


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(b) Multiply magnitude of \vec{F} by r_{\perp} .



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question flag





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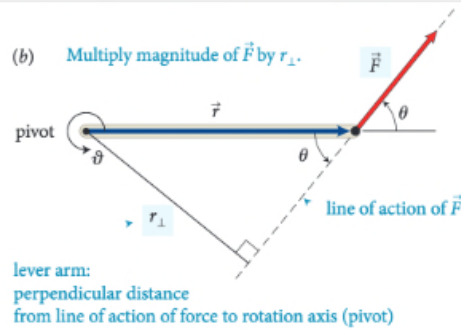
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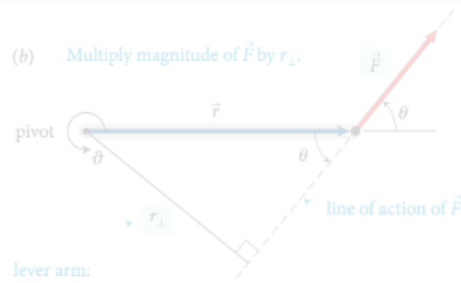
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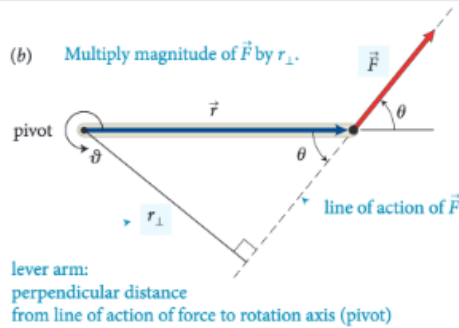
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Brian Lukoff responded to a question in Mazur Chapter 4 Sample that you wanted to know the answer to

21 minutes ago, you asked this question on Perusall:

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Brian Lukoff just responded to the question by saying:

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

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Generally, for rotating bod... 2

Does torque have the s... 3

email notifications

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

21 minutes ago, you asked this question on Perusall:

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

Brian Lukoff just responded to the question by saying:

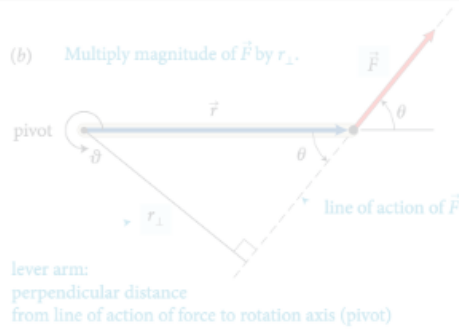
Right - I think there will always be some friction due to the second law of thermodynamics.

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

View conversation

This comment helps my understanding

option 3: mark as answered



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how to get students to participate?

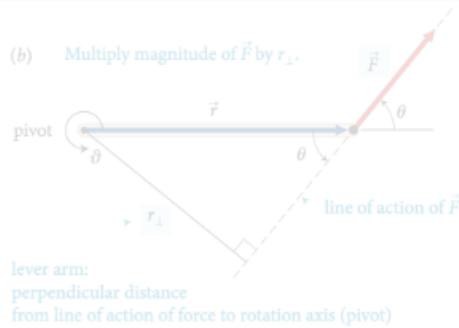
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use combination of

intrinsic and extrinsic motivation drivers

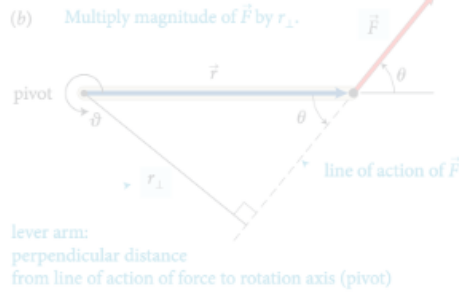
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rubric-based assessment



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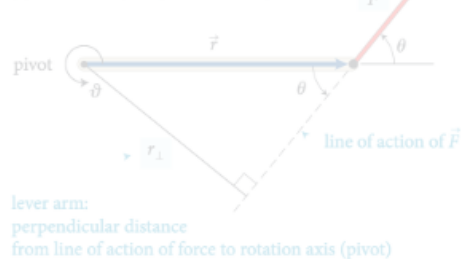
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Enter your comment or question and press Enter

rubric-based assessment

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



lever arm:
perpendicular distance
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- quantity (10–20)

- timeliness (before class)

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- So then do we have a p... 5
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- I don't really understand... 2
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- While I believe I underst... 3
- (a) The change in rotationa...
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- 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)

action of the force and the rotation. So, the torque caused by a force \vec{F} is the product of the force's magnitude and the lever arm distance. It can

- quality (minimum 10)

- timeliness (before class)

- direction (right or left)

over 20,000 annotations!

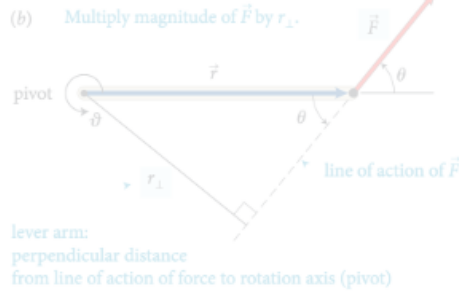
The lever arm distances must now be determined relative to the pivot point. The lever arm distance of a force \vec{F} about a pivot point is zero, and so the torque caused by a force about the left end of the rod is zero. If I choose the pivot at the left end of the rod, the force \vec{F} causes a positive torque about the pivot. The lever arm distance of the force \vec{F} about the left end of the rod is the perpendicular distance from the left end of the rod to the line of action of the force. This distance is equal to the magnitude of the force F times the sine of the angle θ between the rod and the line of action of the force. The lever arm distance is $r_{\perp} = r \sin \theta$. The torque is $\tau = r_{\perp} F = r F \sin \theta$. We obtain the same result if we choose the pivot at the right end of the rod. The sum of the torques about the rod is zero, just like the sum of the forces about the rod is zero.

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?

- Only left, we see th...
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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 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 where a force is exerted, we can eliminate that force from the calculation.

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

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how do you process all of that??

- quantity (minimum 10)
- timeliness (before class)
- distribution (not clustered)

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



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

• quality (though full reliance on interpretation)

fully automated
how do you process all of that??

• timeliness (before class)

• distribution (not clustered)

distance, you can attach a sign to the torque based on the defined parameters of the system. In the following paragraph, they explain how to choose this direction.

This is a great question. To fully understand this, you can think of this in terms of the torque. The torque is $\tau = r \times F$, with r being the distance from the pivot to the point where the force acts. We know that force is a vector, and in regards to "r" it can also be thought of as a 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

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 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_2 . The torque caused by \vec{F}_2 about the left end of the rod is $\tau_2 = r_2 F_2$. This is the same result obtained for the torques about the pivot, and so the sum of the torques about the left end is zero.

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

For a static equilibrium problem, you must choose a reference point to calculate the torques. To choose a reference point, you should choose a point where the net force is zero. So, by putting the reference point at the point where the net force is zero, we can eliminate that force from the calculation.

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

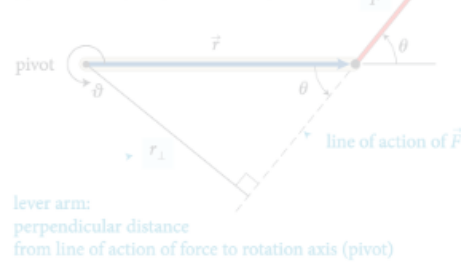
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fully automated assessment

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



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

- 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 just know some sort of direction from the force vector.

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. For example, in a graph, you can explain how to choose the sign of the torque.

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

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 any point 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 result is that the sum of the torques 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. For example, we can choose a reference point at the point of application of a force. In this case, we do not need to consider any force that is exerted at the reference point. So, by putting the reference point at the point of application of a force, we can eliminate that force from the calculation.

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Total number of annotations **16**

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

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

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

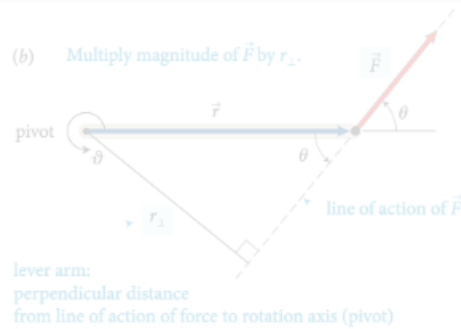
Distribution of annotations **3.8**

0 = clustered, 5 = evenly distributed throughout assignment

Assignment score **1**

scores range from 0 to 3

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



lever arm:
perpendicular distance
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connect pre-class and in-class activities

I don't think you can think of torque as a scalar quantity. Torque is a vector quantity. The lever arm distance both scalar quantities? It seems like we would need to know some sort of direction to calculate torque.

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

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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)

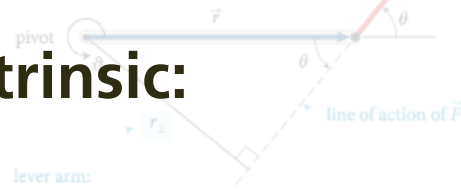
- CP Does that mean that the compass will be distracted from the Earth's magnetic field and use the magnetic field that the current of the wire gives off? 2
- AK Can someone explain why this type of bacteria knows what direction the earth's magnetic fields are facing? 3
- J Does the circular loop of 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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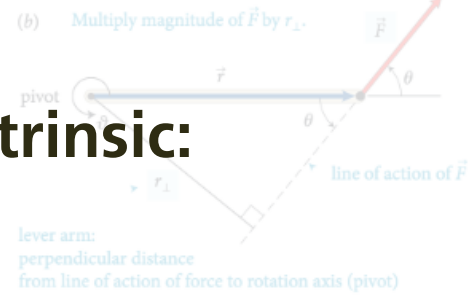
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Enter your comment or question and press Enter

motivating factors

Intrinsic:

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



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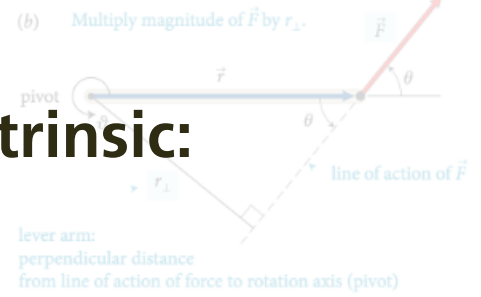
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- tie-in to in-class activity

Extrinsic:

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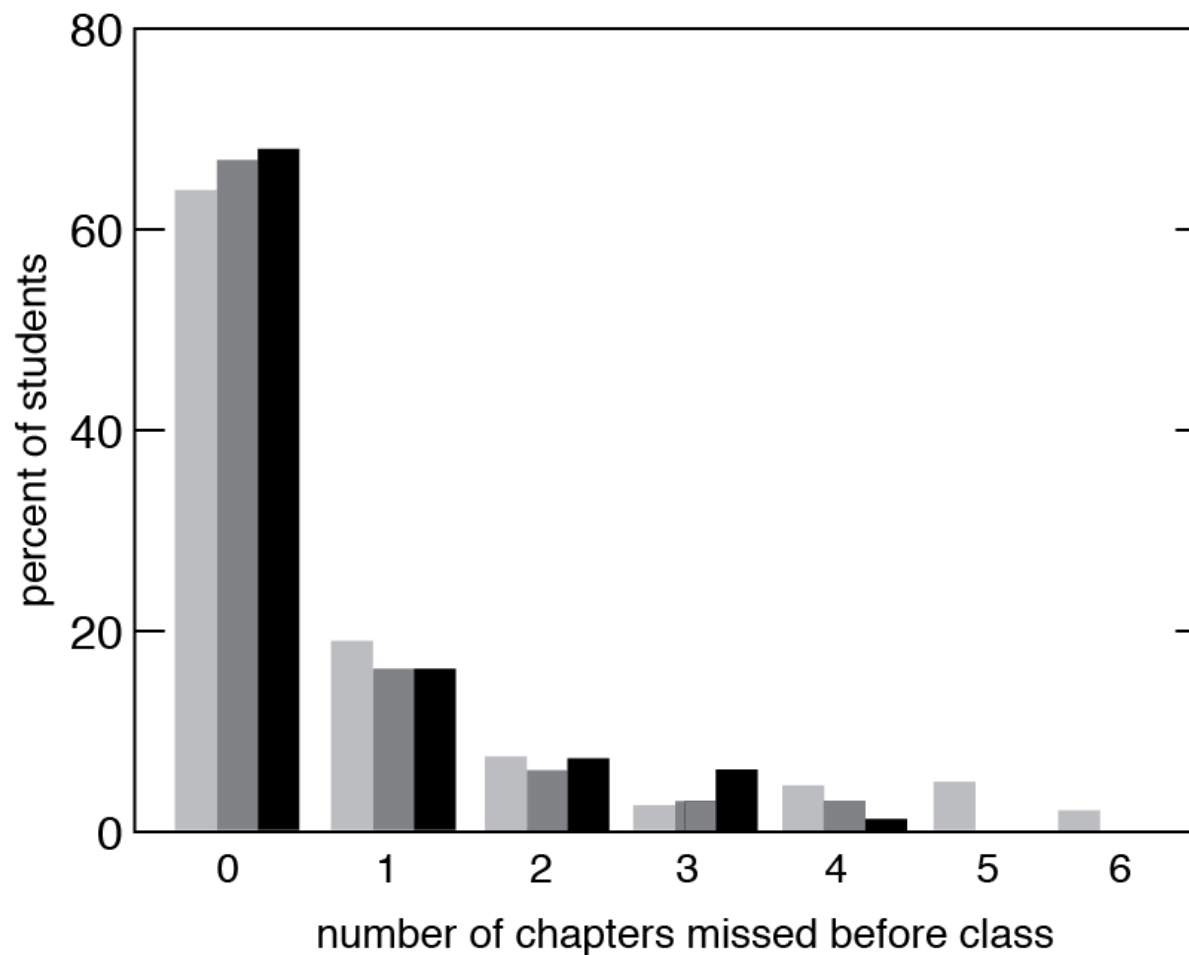
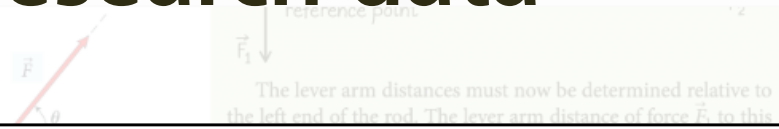
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(b) Multiply magnitude of \vec{F} by r_{\perp} .



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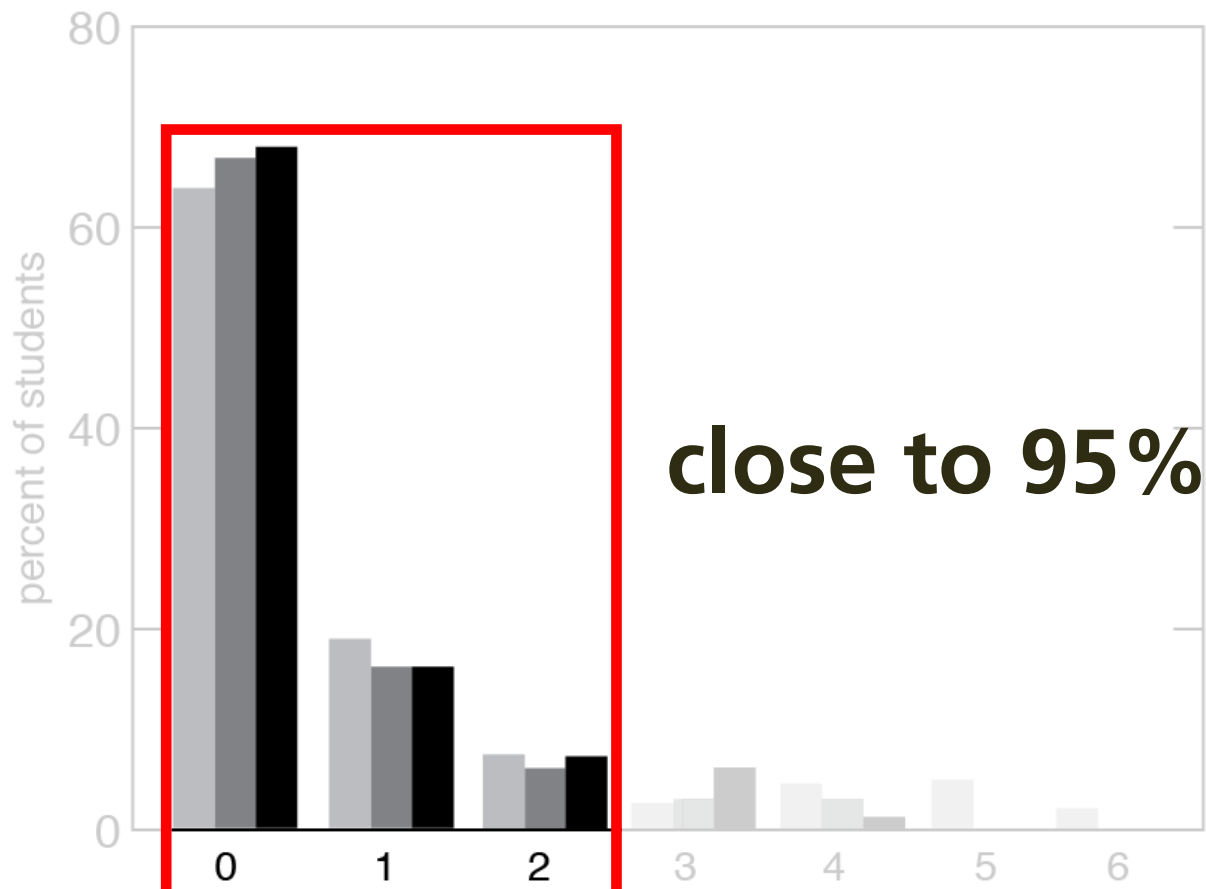
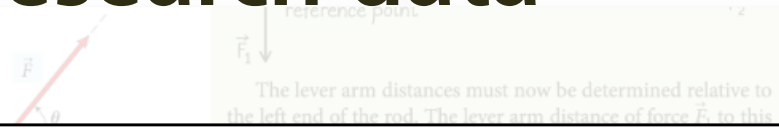
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research data

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close to 95%!

number of chapters missed before class

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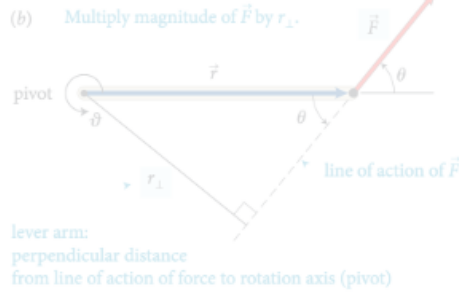
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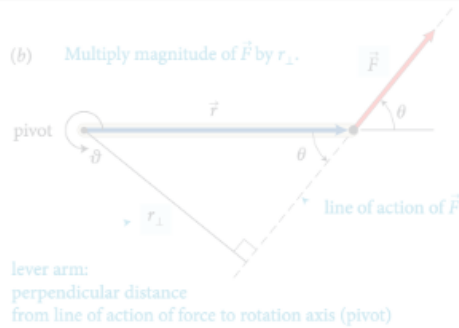
every student prepared for every class

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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 principles 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 you give the block a shove on a very slippery surface, 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 most noticeable on the roughest surface. 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.

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 make surfaces that are nearly frictionless. One way is to use 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:

of friction, objects moving along a 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 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.



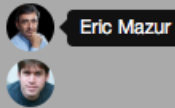
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76 CHAPTER 4 MOMENTUM

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

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Nov 1 4:41 pm



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88 CHAPTER 4 MOMENTUM

Example 4.5 Bullet and bowling ball

Compare the magnitude of the momenta of a 0.010-kg bullet fired from a rifle at 1300 m/s and a 6.5-kg bowling ball lumbering across the floor at 4.0 m/s.

1 GETTING STARTED Momentum is the product of inertia and velocity. I have to calculate this quantity for both the bullet and the bowling ball and then compare the resulting values.

2 DEVISE PLAN Equation 4.6 gives the momentum of an object. To determine the magnitude of the momentum of an object, I must take the product of the inertia m and the speed v : $p = mv$.

3 EXECUTE PLAN Substituting the values given in the problem statement, I get

$$p_{\text{bullet}} = (0.010 \text{ kg})(1300 \text{ m/s}) = 13 \text{ kg} \cdot \text{m/s} \checkmark$$

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With the definition of momentum, we can rewrite Eq. 4.5 in the form

$$p_{u,x,f} - p_{u,x,i} + p_{s,x,f} - p_{s,x,i} = 0. \quad (4.8)$$

If we write $\Delta p_{u,x} \equiv p_{u,x,f} - p_{u,x,i}$ and $\Delta p_{s,x} \equiv p_{s,x,f} - p_{s,x,i}$, Eq. 4.8 takes on the beautifully simple form

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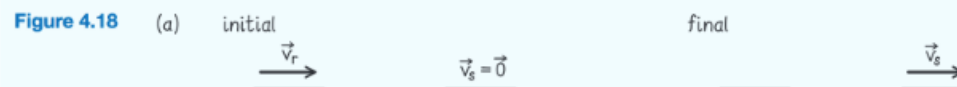
This equation means that, whenever an object of unknown inertia collides with the inertial standard, the changes in the x components of the momenta of the two objects add up to zero. In other words, the change in the x component of the momentum for one object is always the negative of the change for the other.

Example 4.6 Collisions and momentum changes

(a) A red cart with an initial speed of 0.35 m/s collides with a stationary standard cart ($m_s = 1.0 \text{ kg}$). After the collision, the standard cart moves away at a speed of 0.38 m/s. What is the momentum change for each cart? (b) The experiment is repeated with a blue cart, and now the final speed of the standard cart is 0.31 m/s. What is the momentum change for each cart in this second

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88 CHAPTER 4 MOMENTUM

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

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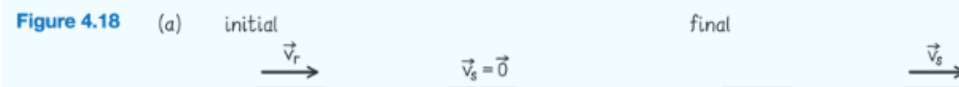
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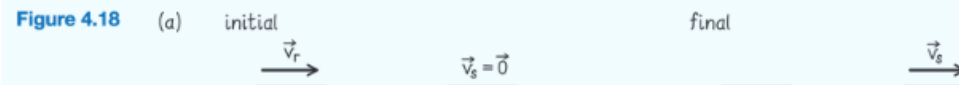
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(a) A red cart with an initial speed of 0.35 m/s collides with a stationary standard cart ($m_s = 1.0$ kg). After the collision, the standard cart moves away at a speed of 0.38 m/s. What is the momentum change for each cart? (b) The experiment is repeated with a blue cart, and now the final speed of the standard cart is 0.31 m/s. What is the momentum change for each cart in this second

collision? (c) If in the collisions $v_{r,x,f} = +0.032$ m/s and $v_{b,x,f} = -0.039$ m/s, what are the inertias of the red and the blue carts?

1 GETTING STARTED I begin organizing the information given in the problem in a picture by showing the initial and final conditions for each of the two collisions (Figure 4.18).



88 CHAPTER 4 MOMENTUM

Example 4.5 Bullet and bowling ball

Compare the magnitude of the momenta of a 0.010-kg bullet fired from a rifle at 1300 m/s and a 6.5-kg bowling ball lumbering across the floor at 4.0 m/s.

1 GETTING STARTED Momentum is the product of inertia and velocity. I have to calculate this quantity for both the bullet and the bowling ball and then compare the resulting values.

2 DEVISE PLAN Equation 4.6 gives the momentum of an object. To determine the magnitude of the momentum of an object, I must take the product of the inertia m and the speed v : $p = mv$.

3 EXECUTE PLAN Substituting the values given in the problem statement, I get

$$p_{\text{bullet}} = (0.010 \text{ kg})(1300 \text{ m/s}) = 13 \text{ kg} \cdot \text{m/s} \checkmark$$

$$p_{\text{bowling}} = (6.5 \text{ kg})(4.0 \text{ m/s}) = 26 \text{ kg} \cdot \text{m/s} \checkmark$$

4 EVALUATE RESULT Surprisingly, the magnitudes of the momenta are very close! I have no way of evaluating momenta because I don't have much experience yet with this quantity. However, the bullet has less inertia and a high speed and the bowling ball has greater inertia and a low speed, so it is not unreasonable that the product of these quantities is similar.

Momentum is a quantitative measure of “matter in motion” and depends on both the amount of matter in motion and how fast that matter is moving. Momentum is very different from inertia. A truck, for example, has greater inertia than a fly (it has a higher resistance to a change in its velocity), but if the truck is at rest and the fly is in motion, then the magnitude of the fly's momentum is larger than that of the truck, which is zero. In Example 4.5, the inertias of the bullet and the bowling ball are very different, yet their momenta are similar. Conceptually you can think of an object's momentum as its capacity to affect the motion of other objects in a collision.

With the definition of momentum, we can rewrite Eq. 4.5 in the form

$$p_{u,x,f} - p_{u,x,i} + p_{s,x,f} - p_{s,x,i} = 0. \quad (4.8)$$

If we write $\Delta p_{u,x} \equiv p_{u,x,f} - p_{u,x,i}$ and $\Delta p_{s,x} \equiv p_{s,x,f} - p_{s,x,i}$, Eq. 4.8 takes on the beautifully simple form

$$\Delta p_{u,x} + \Delta p_{s,x} = 0. \quad (4.9)$$

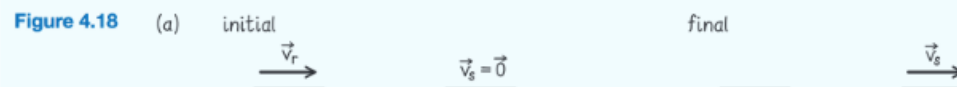
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Brian Lukoff responded to your comment: **Right - I think there will always be some friction due to the second law of thermodynamics.**

a few seconds ago

76 CHAPTER 4 MOMENTUM

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4.2 Inertia

Brian Lukoff responded to your comment: **Right - I think there will always be some friction due to the second law of thermodynamics.**

a few seconds ago

+1 ? No friction at all seems impossible. Isn't there always some friction in any real case.

Nov 1 12:03 pm

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

Nov 1 12:09 pm

Enter your comment or question and press Enter

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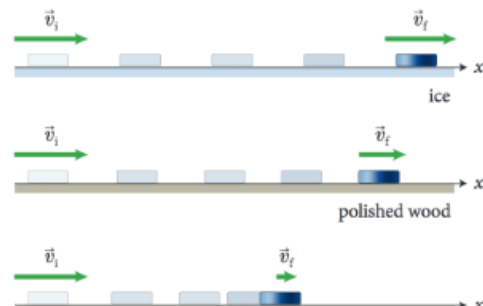


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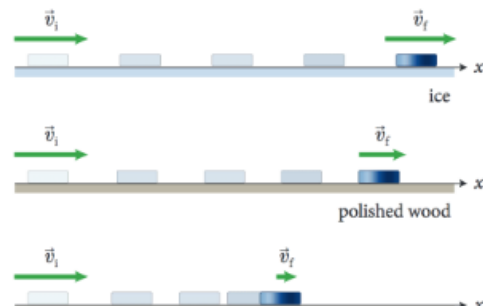


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Annotate some text

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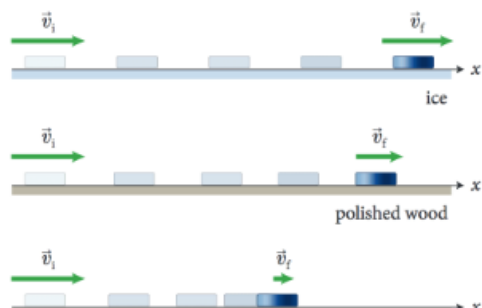


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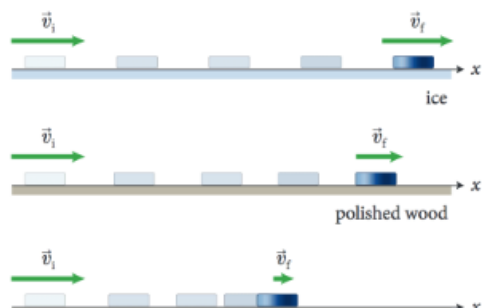


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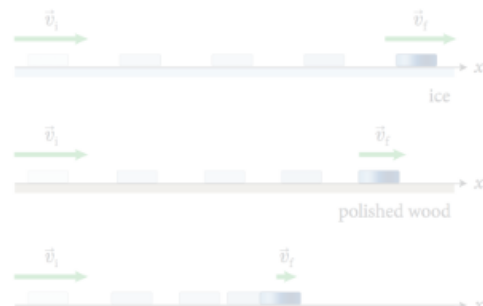
1. post a question
2. answer someone else's question
3. check email and try out email interface

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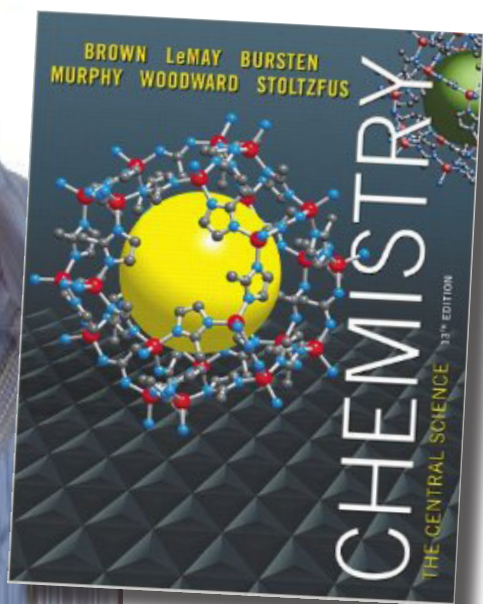
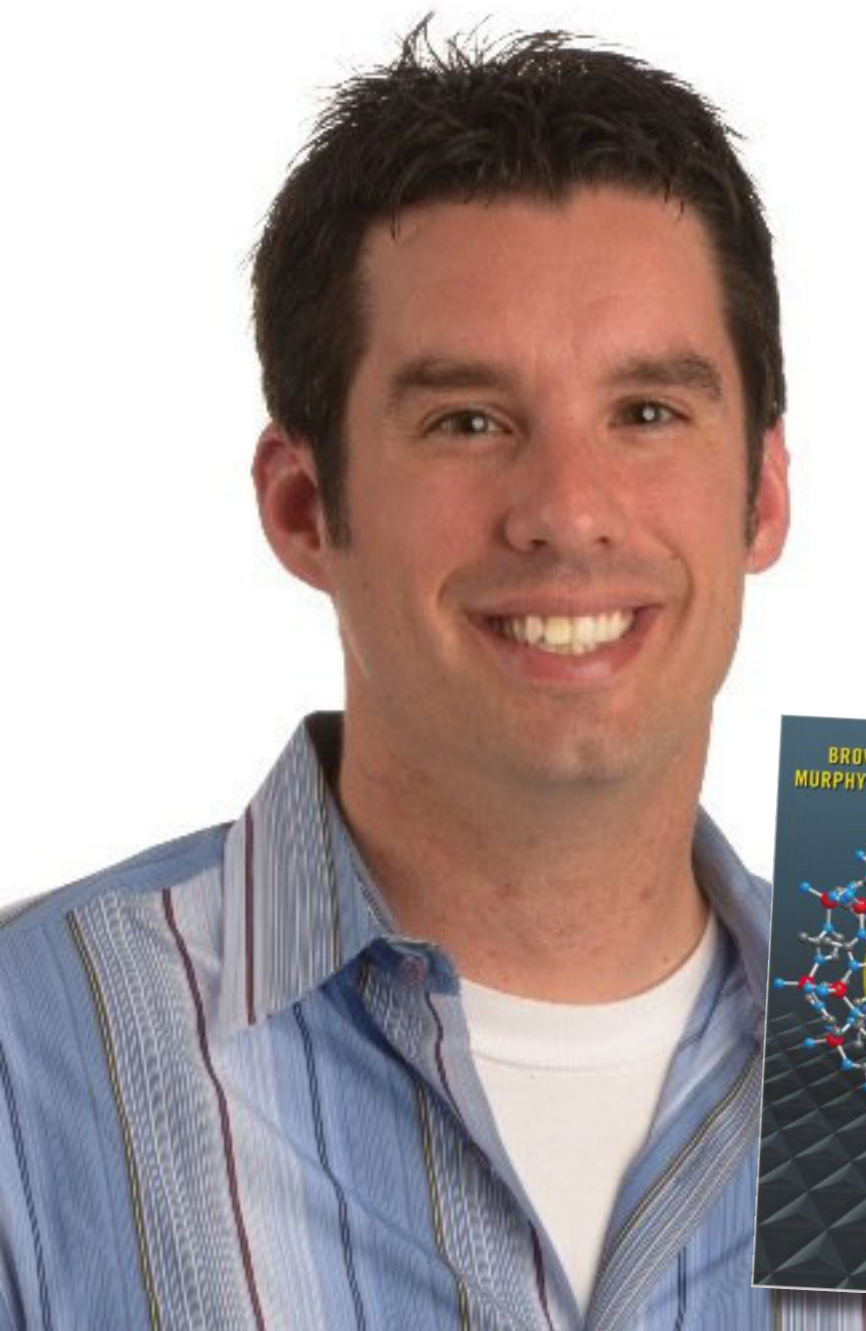
4.2 Inertia

CHEM1210: General Chemistry

Matt Stoltzfus
Ohio State University

525 students

Brown Lemay 13th ed (Pearson)

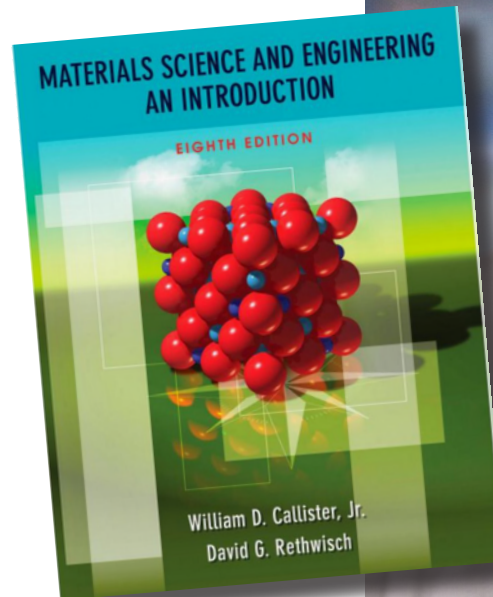


MSE220 : Introduction to Materials and Manufacturing

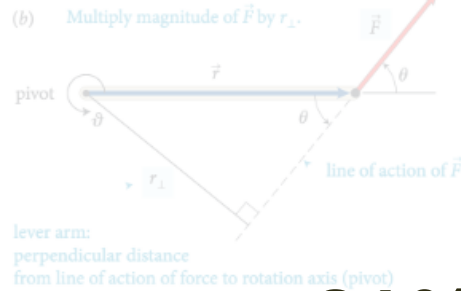
Steve Yalisove
University Michigan

74 students

McCallister 8th ed (Wiley)



additional research data



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

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 F_1 and F_2 . To account for the signs of the torques due to the forces, we have $r_1(F_1 + F_2) - (r_1 + r_2)F_2 = r_1F_1 - r_2F_2$. 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

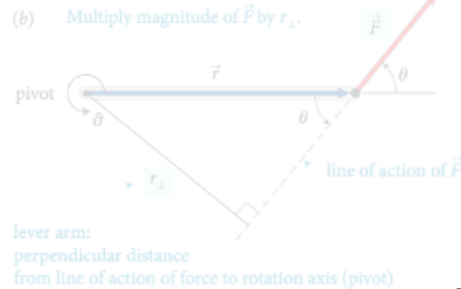
Three forces are exerted on the lever of Figure 12.7. Forces \vec{F}_1 and \vec{F}_2 are equal in magnitude, and the magnitude of \vec{F}_3 is half as great. Force \vec{F}_1 is horizontal, \vec{F}_2 and \vec{F}_3 are vertical, and the lever makes an angle of 45° with the horizontal. Do these forces cause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

• Engagement: 81% spend 2–6 hrs/wk reading

- 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
- I understand partially w... 3
- In this class, we always emp...
- 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 ...
- Torque is the ability of a forc...
- The type of diagram to use d...
- It sounds like it is sayin... 3
- So then do we have a p... 5
- Since torque is the cross pro...
- The right-hand rule can al... 3
- I don't understand how ... 3
- Orientation-based descriptio...
- I don't really understand... 2
- How small is small? As ... 3
- I think it would be slightly ...
- While I believe I underst... 3
- (a) The change in rotationa...
- As we saw earlier in the chap...
- Objects executing motion ar...
- 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
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additional research data



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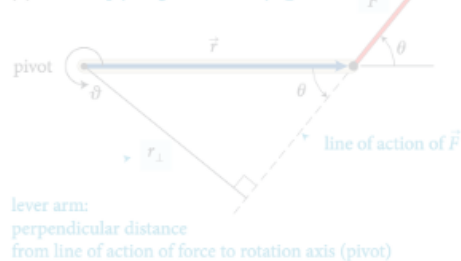
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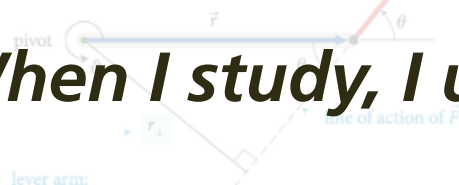
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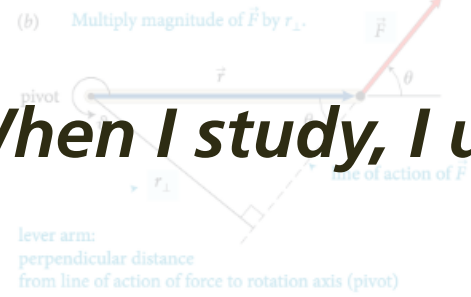
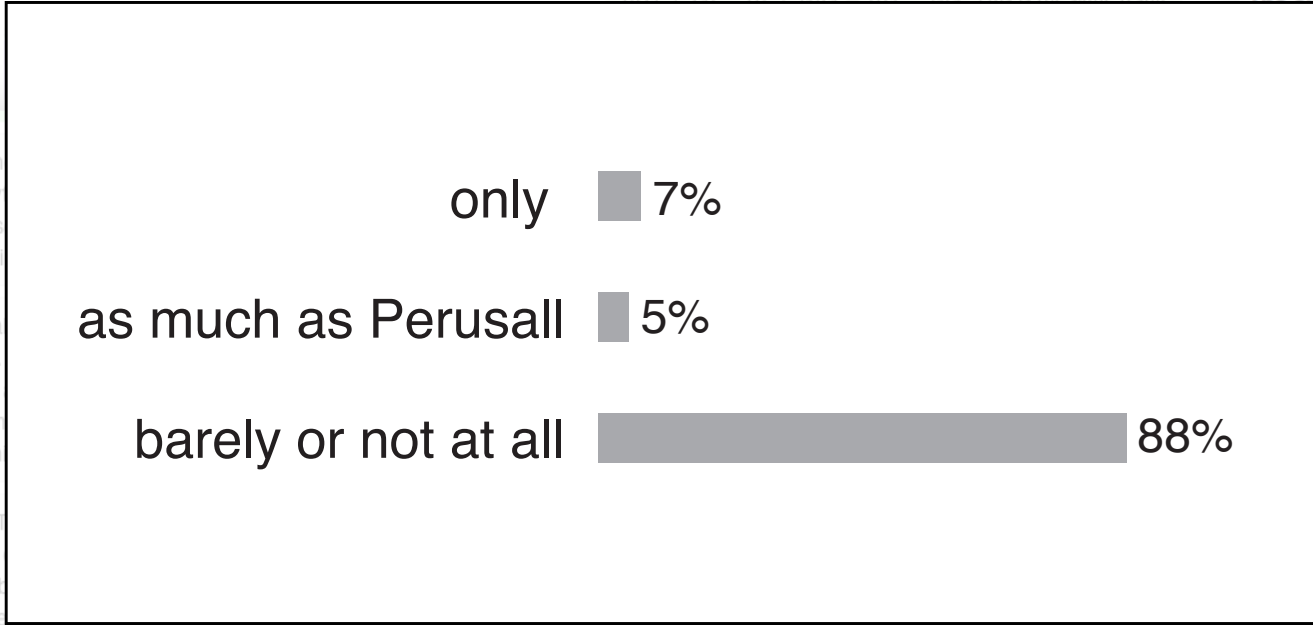
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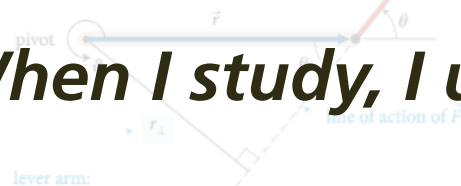
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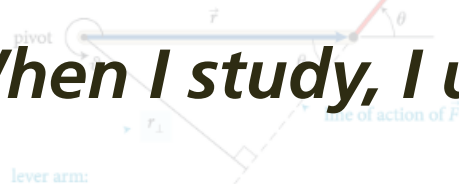
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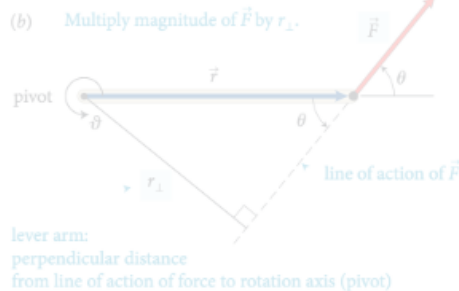
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lever arm:
perpendicular distance
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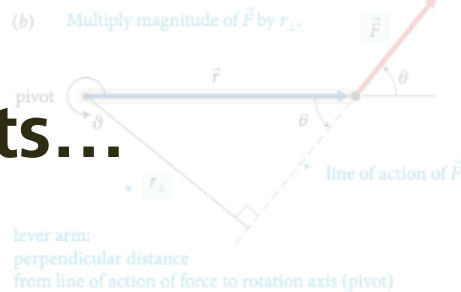
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Students...



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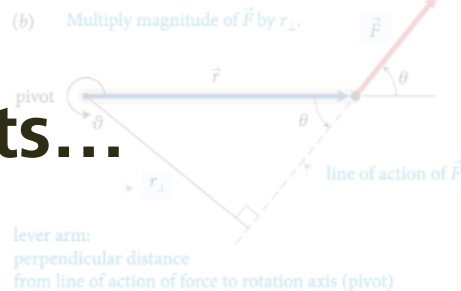
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- read the textbook



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Students...

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- learn how to read

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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:

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

Students...

- read the textbook
- learn how to read
- learn how to read critically

CONCEPTS

(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 $r_{\perp}F$ and as rF_{\perp} .

Lever arm distance also 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 in equilibrium, 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.

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Students...

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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 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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Students...

- read the textbook
- learn how to read
- learn how to read critically
- participate in a collaborative experience
- get more out of their classes

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

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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. It also plays 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.

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Students...

- read the textbook
- learn how to read
- learn how to read critically
- learn how to study and work collaboratively
- get more out of their classes

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



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action of the force and the axis of rotation, the torque caused by a force exerted on an object is the product of the magnitude of the force and the lever arm. It is written as $\tau = r_{\perp}F$. As a result, the torque depends on the magnitude of the force and the angle θ . Figure 12.1 shows the torque caused by \vec{F}_1 about the pivot. The torque is in the direction of increasing θ , and so it is positive. The torque caused by \vec{F}_2 is negative, and so it is in the direction of decreasing θ . The sum of the two torques about the pivot is then $\tau = r_1F_1 - r_2F_2$. As we've seen, the two torques are equal in magnitude when the rod is in equilibrium, 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 12.1 and 12.2, we used the pivot to calculate the lever arm distance. This is a natural choice because, in these cases, the pivot is stationary. It also plays a role for stationary objects that are 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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Example 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. This result can be stated as follows:

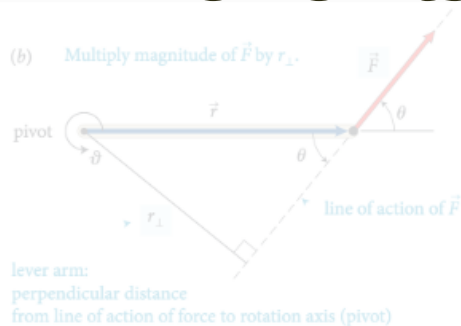
Principle of Torques: If an object is in equilibrium, the sum of the torques about any reference point is zero. It pays to choose a reference point that simplifies the calculation. As you have seen, we do not need to consider a force exerted at the reference point, because the lever arm distance from the reference point to the point of application of the force is zero.

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



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_1 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.

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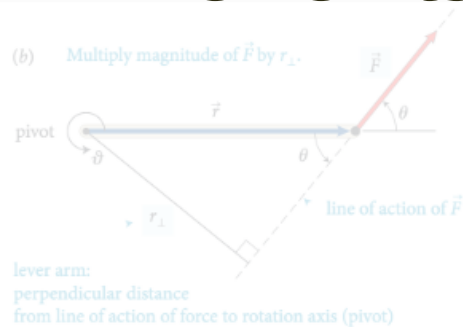


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• time recovery

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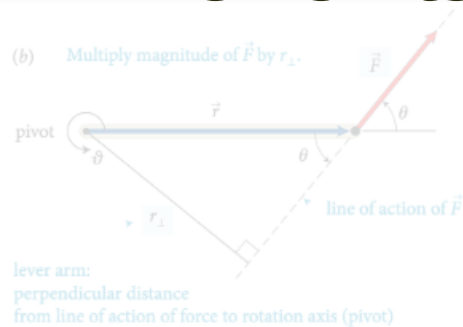


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(b) Multiply magnitude of \vec{F} by r_{\perp} .



lever arm:
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- time recovery

- improved use of class time

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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, 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} .



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 , and as $r_{\perp}F$.

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 $r_1F_1 + (-r_2F_2)$. We've seen that 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 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).

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.



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

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- time recovery
- improved use of class time
- enhanced respect and understanding for students

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



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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 $r_1F_1 + (-r_2F_2)$. We've seen that the two torques are equal in magnitude, so the sum of the two 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 crane can be supported at one end, and a seesaw can be supported at the other 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).

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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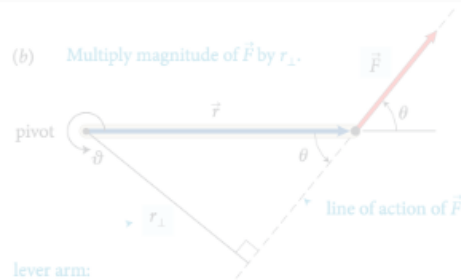
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- time recovery
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all at no cost & no additional effort!

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



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

Like other rotational quantities, torque carries a sign that depends on the choice of direction for increasing ϑ . In Figure 12.4, for example, the torque caused by \vec{F}_1 about the pivot tends to rotate the rod in the direction of increasing ϑ and so is positive; the torque caused by \vec{F}_2 is negative. The sum of the two torques about the pivot is then $r_1F_1 + (-r_2F_2)$. As we've seen, the two torques are in magnitude equal to the sum of the forces F_1 and F_2 multiplied by the distance from the pivot to the point of application of the force. If the rod is at rest, the sum of the torques about the pivot is zero, and so is the 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.

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The sum of the torques about any point is zero. This is true for any object that is not rotating. 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.



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follow up questions?
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