

# Confessions of a converted lecturer



21st Annual IAMSE Meeting  
University of Vermont  
Burlington, VT, 11 June 2017





# Confessions of a converted lecturer



**@eric\_mazur**

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11/11/2019

What is the difference between a point and a line?

- A point is a location in space.
- A line is a set of points that extend infinitely in two directions.

The points on a line are called points on the line.

The points on a line are called points on the line.

The points on a line are called points on the line.

1	2	3	4	5
1	2	3	4	5
6	7	8	9	10
11	12	13	14	15
16	17	18	19	20
21	22	23	24	25
26	27	28	29	30
31	32	33	34	35
36	37	38	39	40
41	42	43	44	45
46	47	48	49	50
51	52	53	54	55
56	57	58	59	60
61	62	63	64	65
66	67	68	69	70
71	72	73	74	75
76	77	78	79	80
81	82	83	84	85
86	87	88	89	90
91	92	93	94	95
96	97	98	99	100

11/11/2019

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11/11/2019

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11/11/2019

What is the difference between a point and a line?

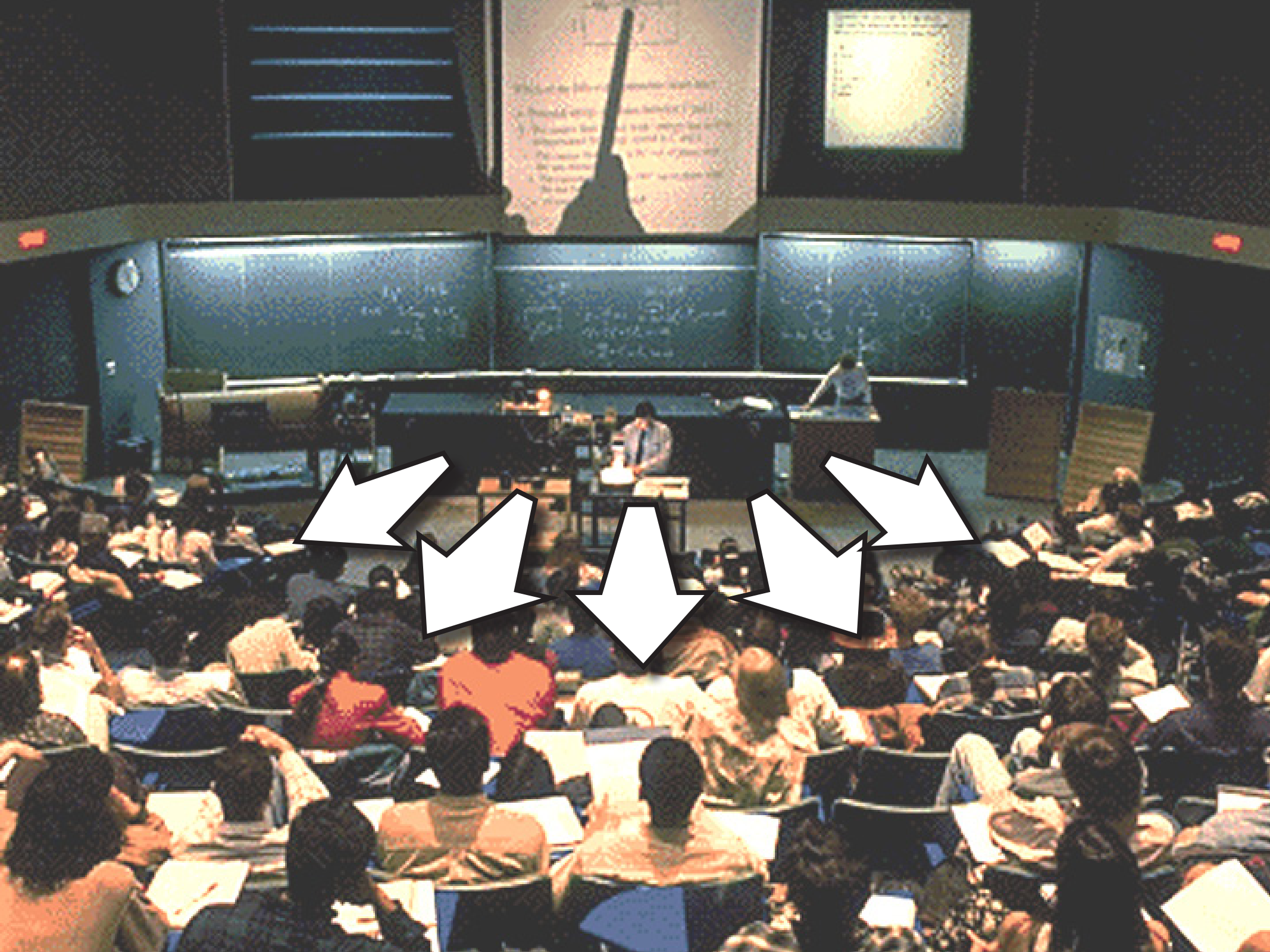
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**an illusion. . .**









# **1. transfer of information**





**1. transfer of information**

**2. assimilation of that information**





**1. transfer of information (in class)**

**2. assimilation of that information**





1. transfer of information (in class)

2. assimilation of that information (out of class)





**Should focus  
on THIS!**

1. transfer of information (in class)

**2. assimilation of that information (out of class)**





**1. transfer of information (in class)**

**2. assimilation of that information (out of class)**





**1. transfer of information (out of class)**

**2. assimilation of that information (in class)**



The word "Peer" is written in a large, white, sans-serif font with a light blue outline. A dashed yellow line with arrowheads at both ends forms a circle around the two 'e's. A dotted blue line starts from the bottom left, passes through the 'e's, and ends with an arrowhead pointing towards the 'r'.

# Peer

**1. transfer of information (out of class)**

**2. assimilation of that information (in class)**

The word "INSTRUCTION" is written in a white, sans-serif font, tilted upwards from left to right. A dotted blue line starts from the bottom left, passes through the 'e's in "Peer", and ends with an arrowhead pointing towards the 'I' in "INSTRUCTION".

# INSTRUCTION



**question**



**question**



**think**



**question**



**think**



**poll**



**question**



**think**



**poll**



**discuss**



**question**



**think**



**poll**



**discuss**



**repoll**



**question**



**think**



**poll**



**discuss**

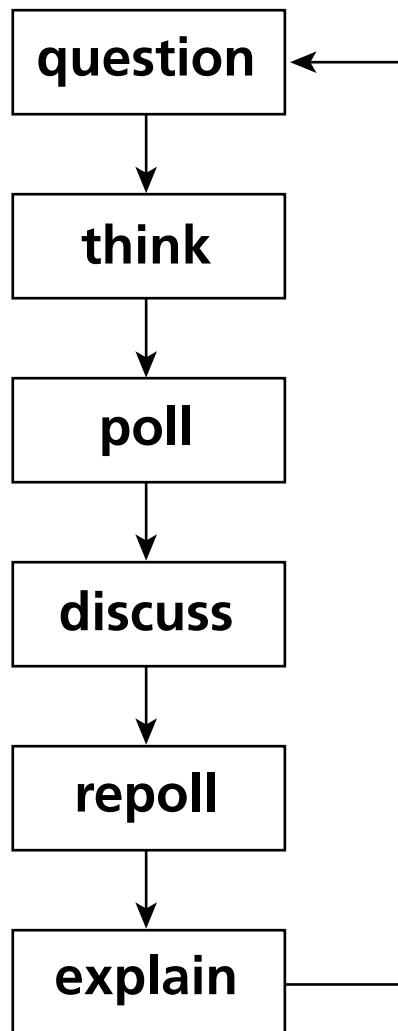


**repoll**



**explain**







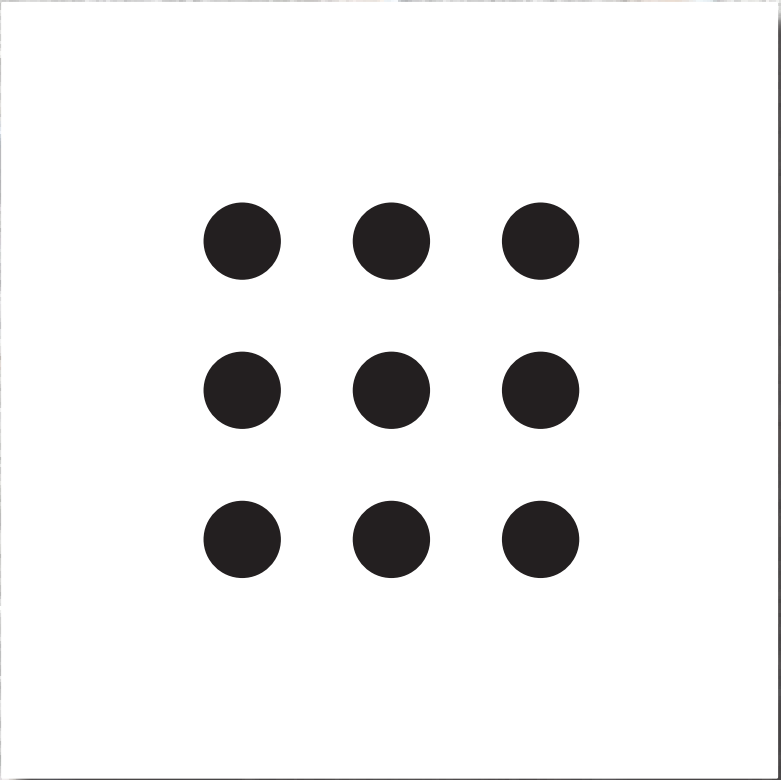
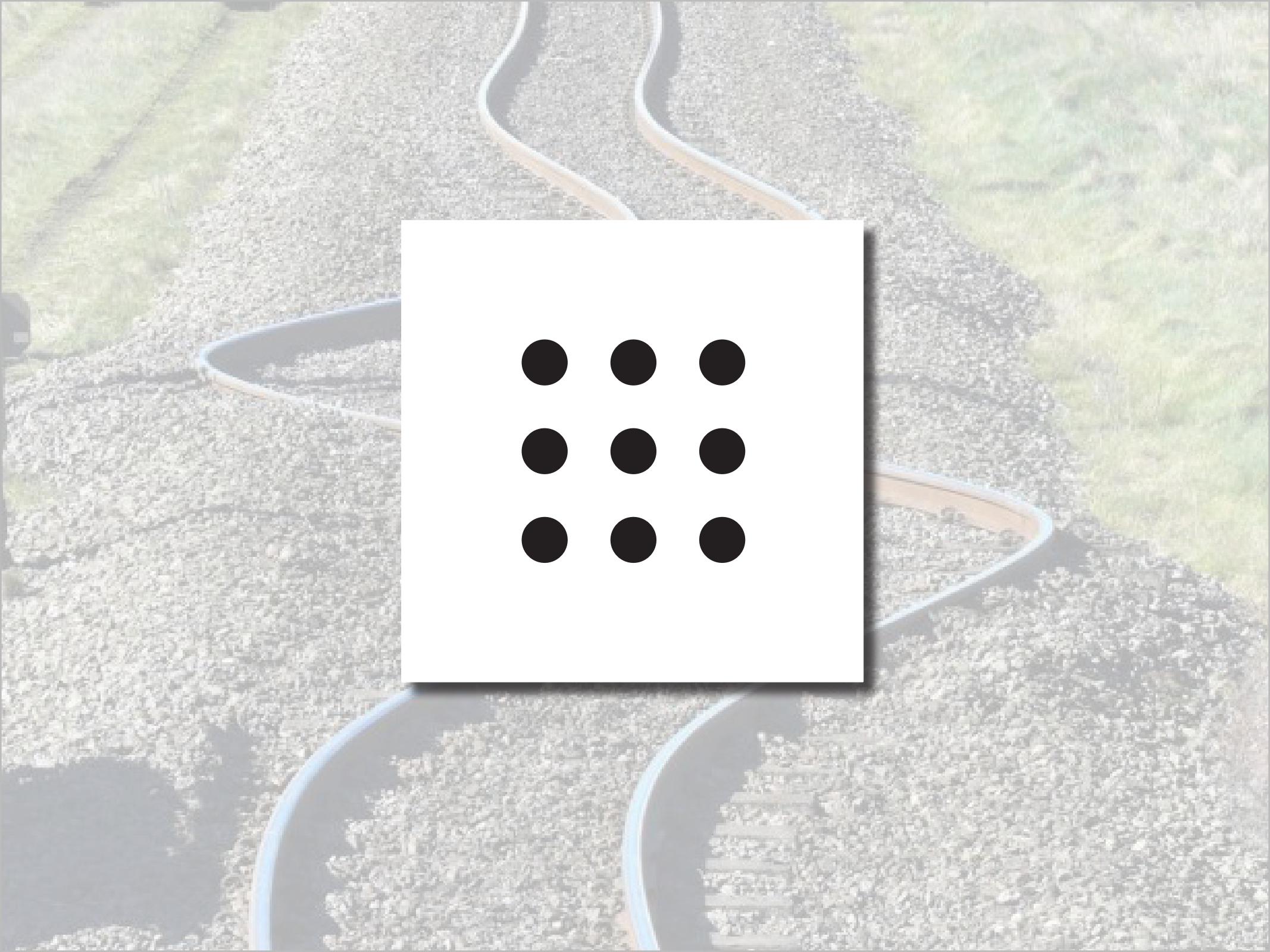


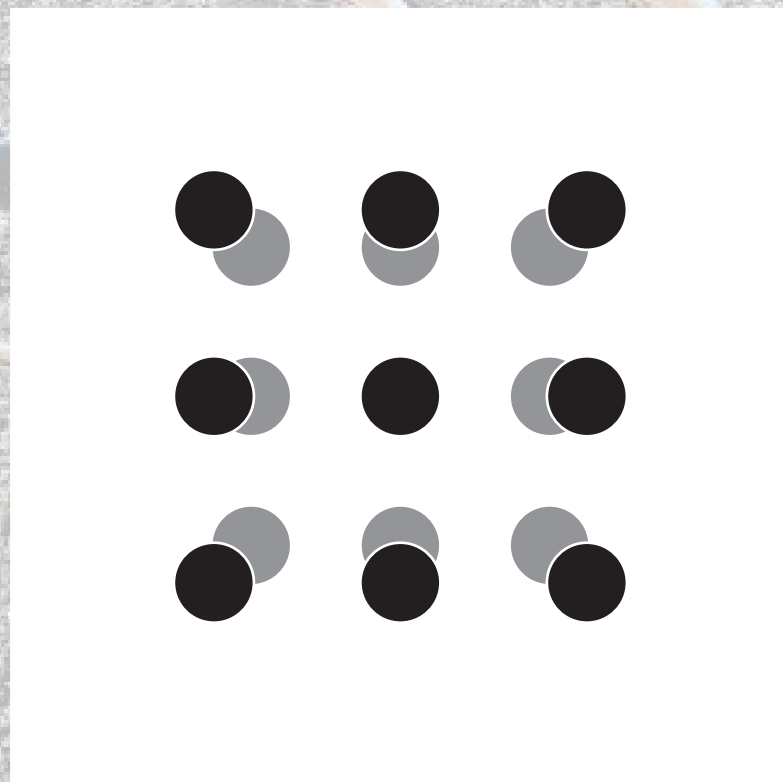


A photograph of a railway track with a wavy, undulating path, illustrating the concept of thermal expansion. The track is composed of gravel and wooden sleepers, and the rails are visible. The track is set against a background of green grass. The text "thermal expansion" is overlaid on the image.

**thermal expansion**

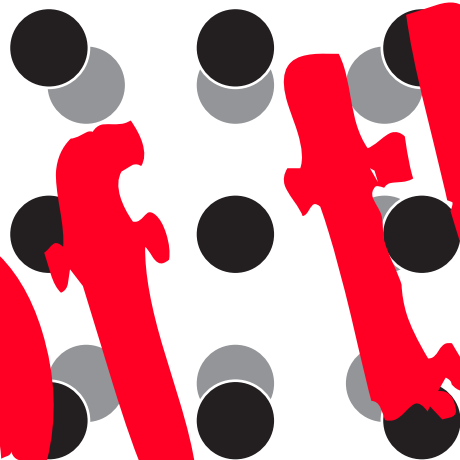








**all of them**



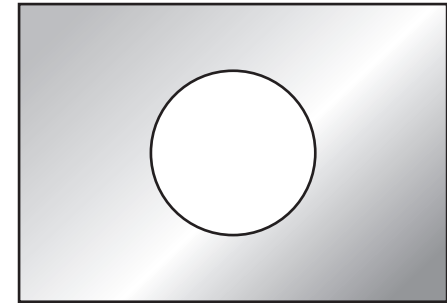
**Consider a rectangular metal plate  
with a circular hole in it.**





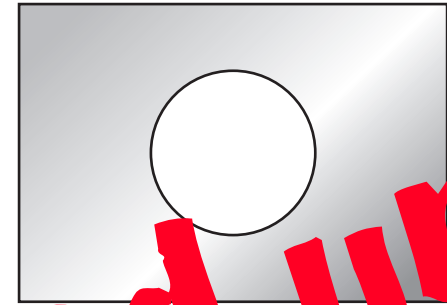
**Consider a rectangular metal plate with a circular hole in it.**

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



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

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



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

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

**you got all fired up!**



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



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

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

**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**



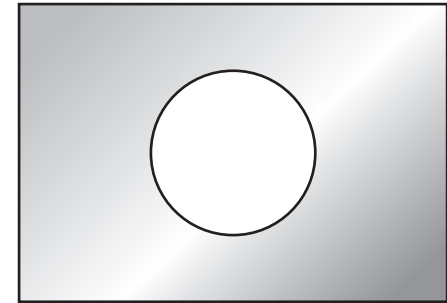
**Before I tell you the answer, let's analyze what happened.**

**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**

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

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



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



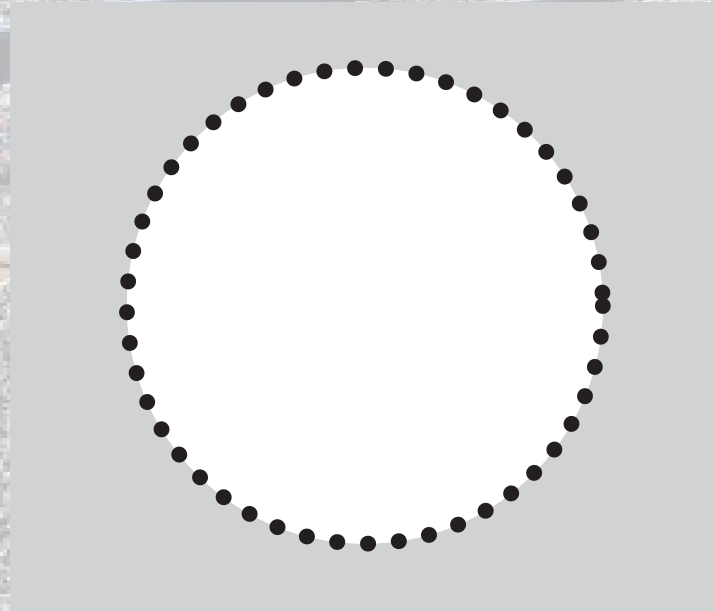
**Consider a rectangular metal plate with a circular hole in it.**



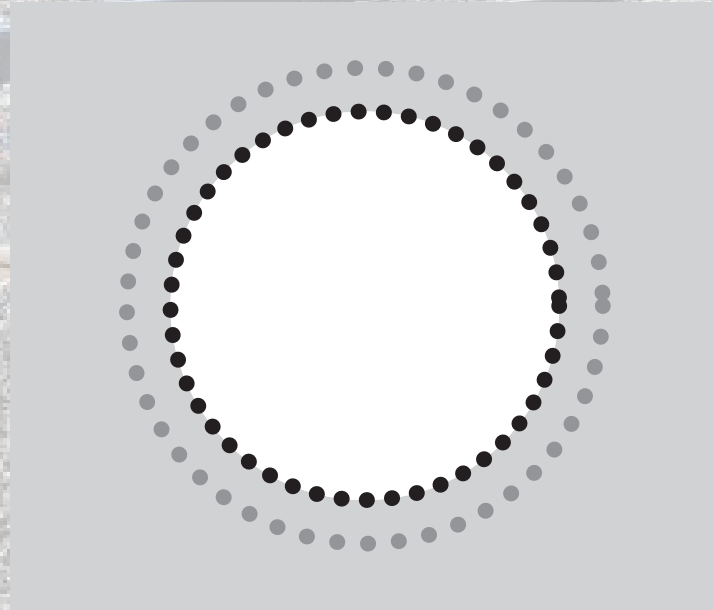
**When the plate is uniformly heated, the diameter of the hole**

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

**consider atoms at rim of hole**

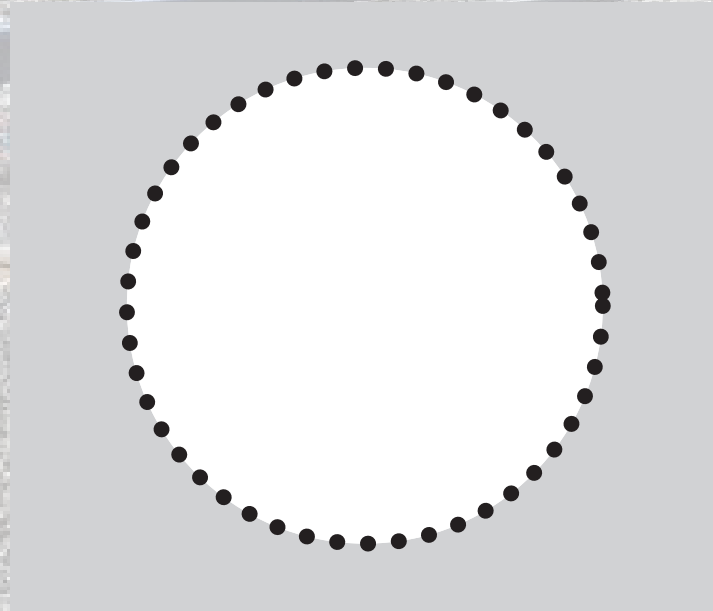


**consider atoms at rim of hole**

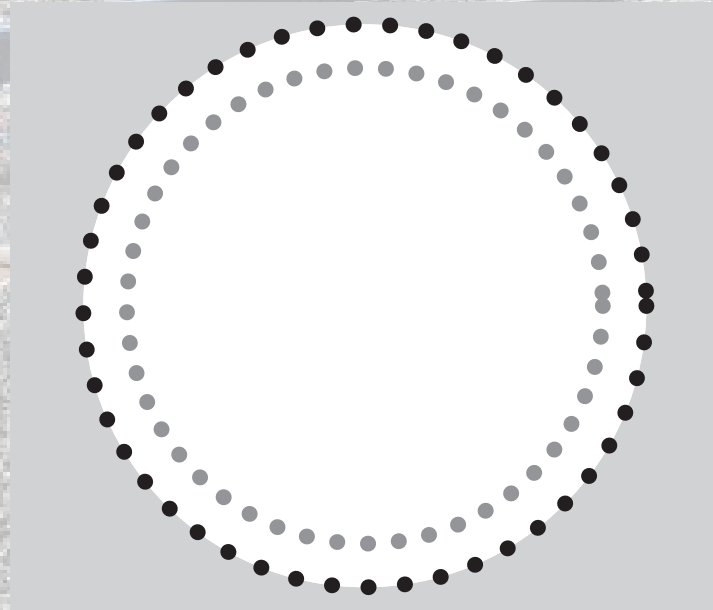




**consider atoms at rim of hole**



**consider atoms at rim of hole**



consider atoms at rim of hole

**you won't forget this**



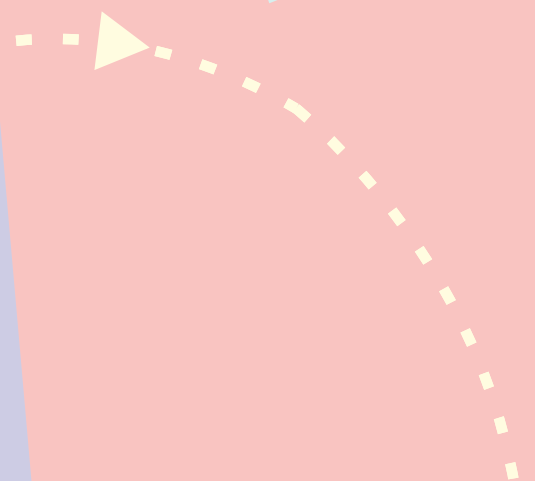
Peer

A decorative dashed yellow line with arrows at both ends, curving around the word "Peer". Small blue dots are scattered along the path of the line.

back to pl

A decorative dotted blue line that starts near the word "back" and extends diagonally downwards towards the word "INSTRUCTION".

INSTRUCTION

A decorative dashed yellow line with an arrow pointing towards the word "INSTRUCTION".

**Higher learning gains**

INSTRUCTION

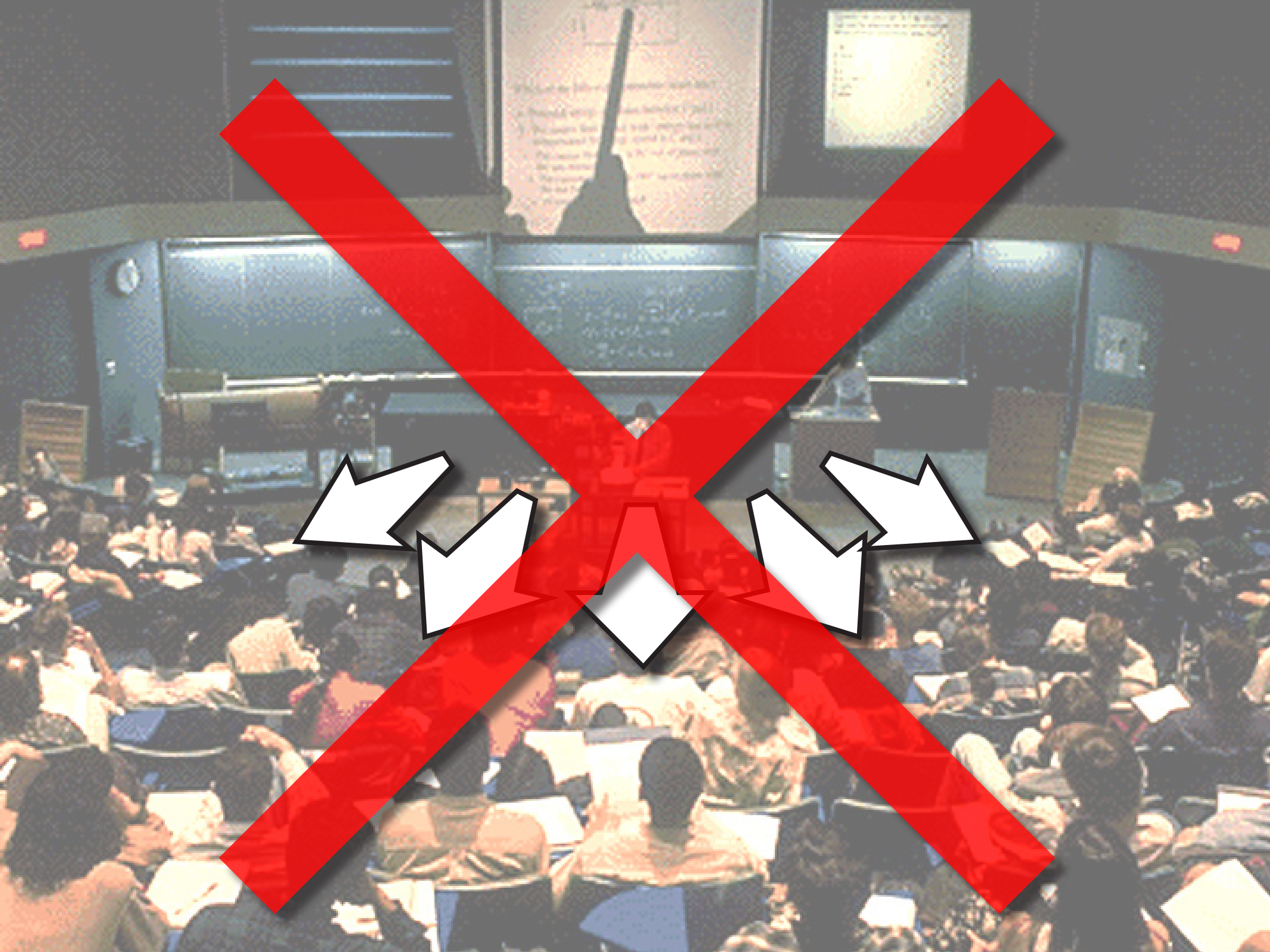


**Higher learning gains**

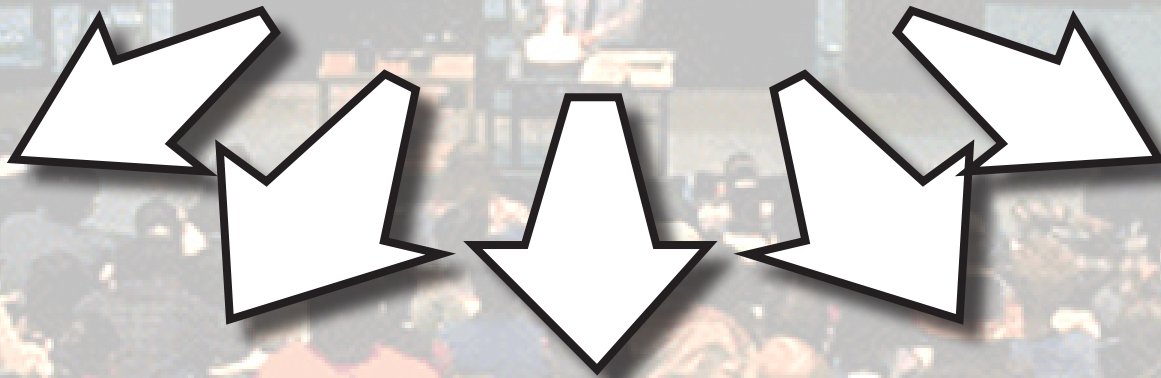
**Better retention**

**INSTRUCTION**





**how to effectively transfer information outside classroom?**









**but...**



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



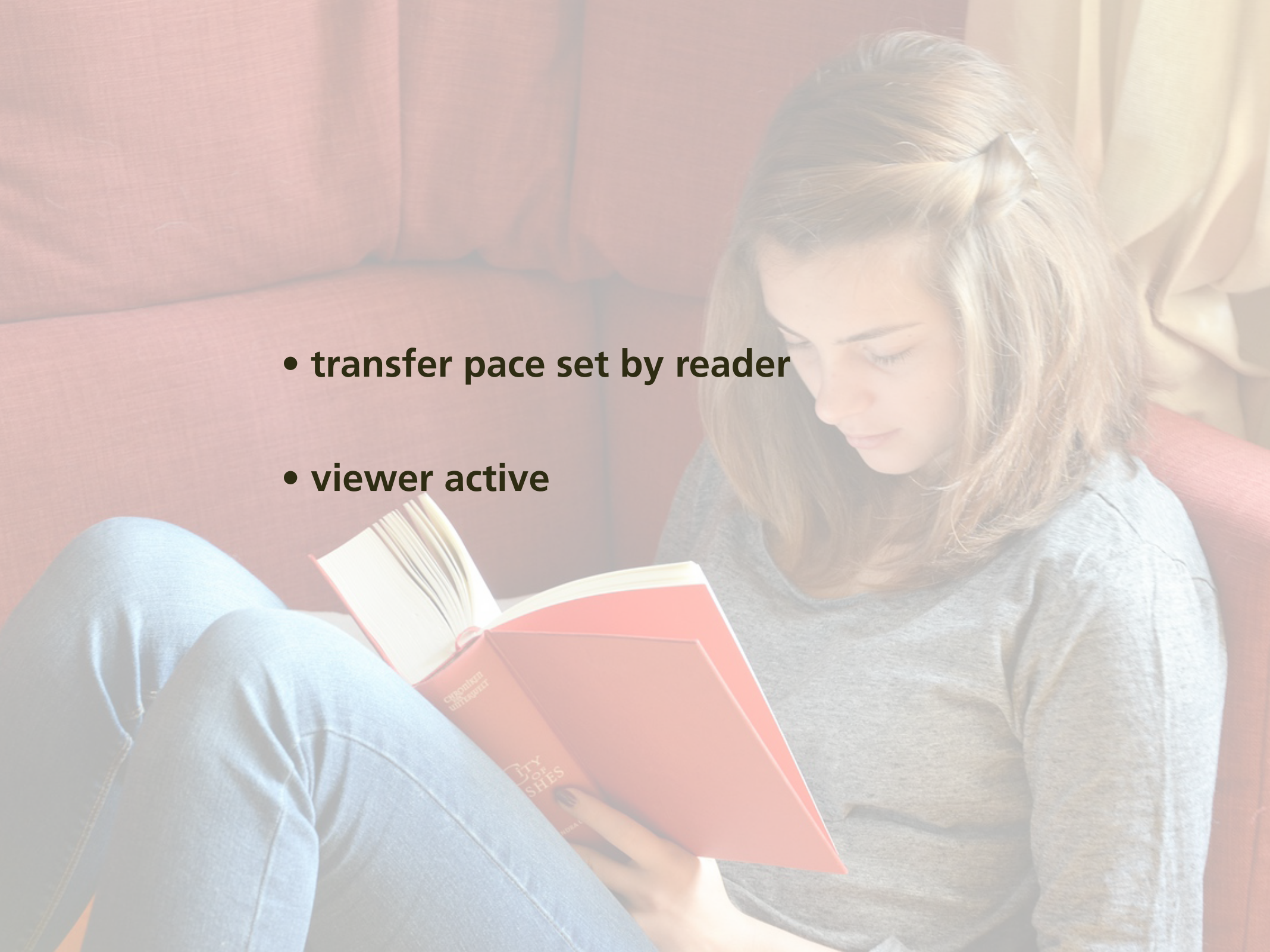


**we're simply moving this outside classroom!**








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



**but...**







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





**want:**  
***every student prepared for every class***





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



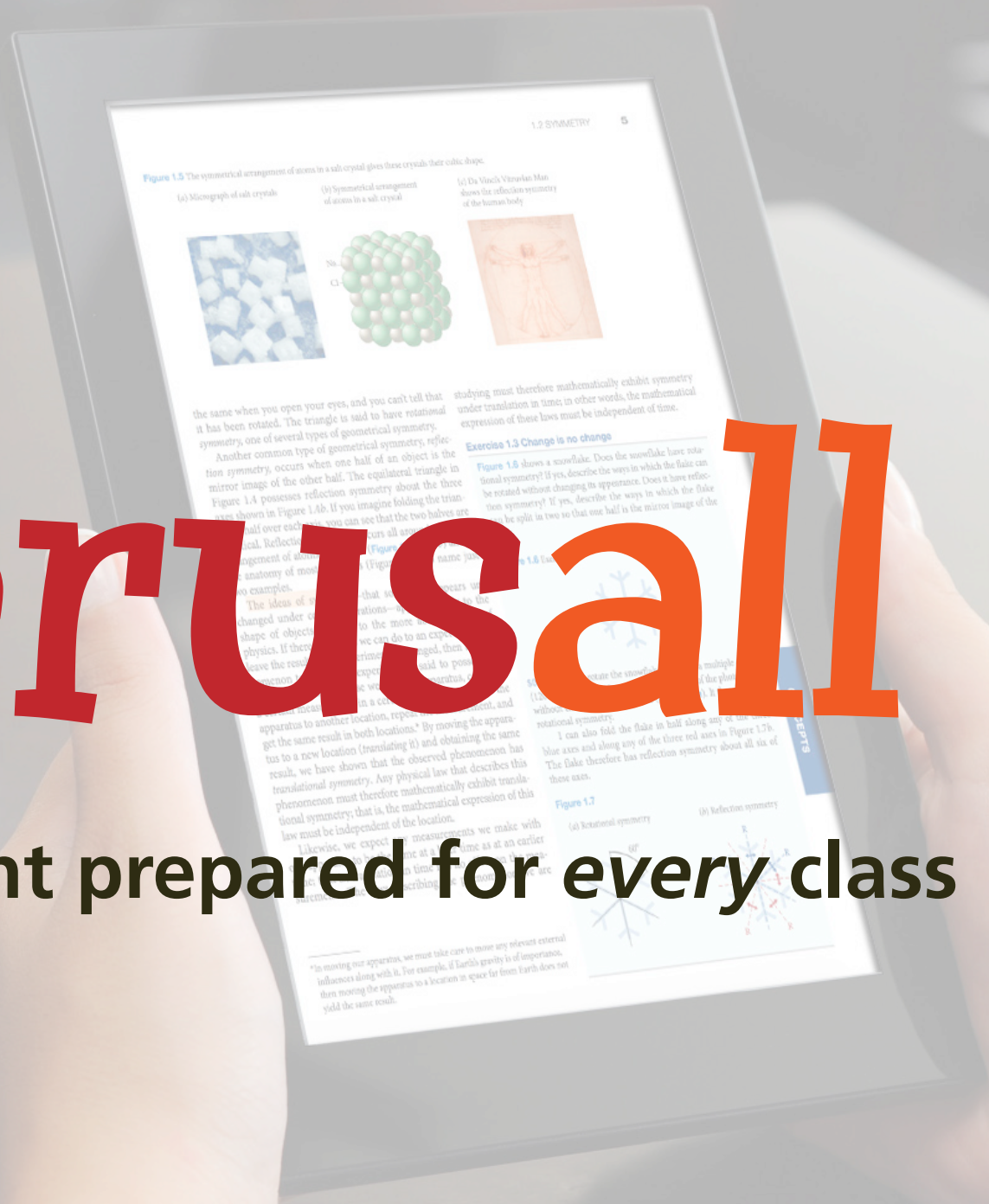
A stylized illustration of a classroom. Several students are seated at rows of desks, facing forward. The students are depicted in various colors (yellow, green, blue, purple, pink, light green) and are holding pens or pencils, suggesting they are taking notes or participating in a lesson. The background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

**Solution**

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

# Perusall

every student prepared for every class



## 76 CHAPTER 4 MOMENTUM

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

## 4.1 Friction

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

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

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



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



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

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

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



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



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

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



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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 an air hockey table, in which the puck is cushioned with a thin layer of air that reduces friction. Alternatively, one can use wheeled carts with low-friction bearings on an ordinary track. Figure 4.2 shows low-friction carts you may have encountered in your physics lab. Although there is still some friction between the wheels and the tracks and for the track itself, the friction is so small that it can be neglected. For example, if the track is perfectly horizontal, the carts move along its length with constant velocity. In other words:

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

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



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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 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:

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

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



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

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

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...opens chat window



Enter your comment or question and press Enter

## 76 CHAPTER 4 MOMENTUM

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

## 4.1 Friction

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

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

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



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



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

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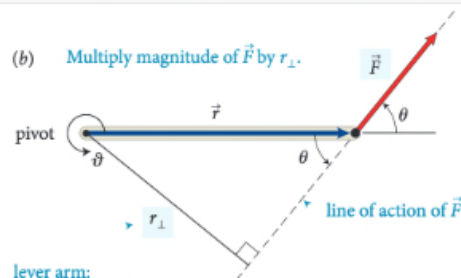


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(b) Multiply magnitude of  $\vec{F}$  by  $r_{\perp}$ .



lever arm:  
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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  $\vartheta$ . 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  $\vartheta$  and so is positive; the torque caused by  $\vec{F}_2$  is negative. The sum of the two torques about the pivot is then  $r_1F_1 + (-r_2F_2)$ . As we've seen, the two torques are equal in magnitude when the rod is balanced, and so the sum of the torques is zero. When the sum of the torques is not zero, the rod's rotational acceleration is nonzero, and so its rotational velocity and angular momentum change.

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

### Exercise 12.1 Reference point

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

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

reference point



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

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

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

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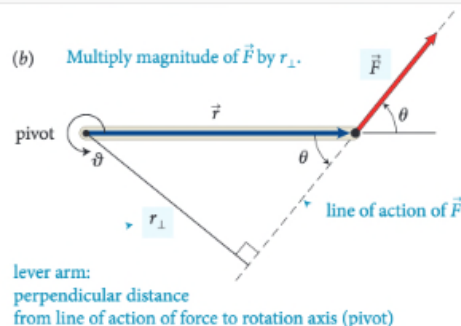
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### Example 12.2 Torques on lever

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



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



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Enter your comment or question and press Enter

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"helps me" flag



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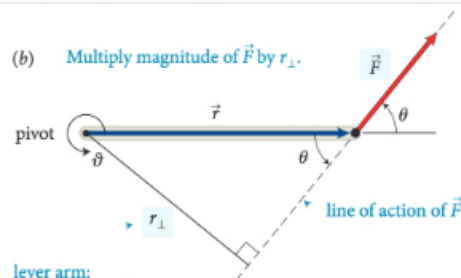
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# email notifications

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:

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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.

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

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## option 2: view chat

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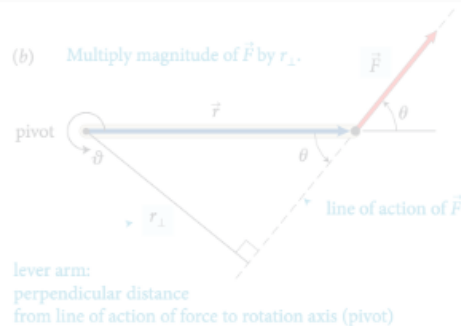
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## option 3: mark as answered

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# how to get students to participate?

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Oct 20 12:09 am

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Oct 22 8:48 pm

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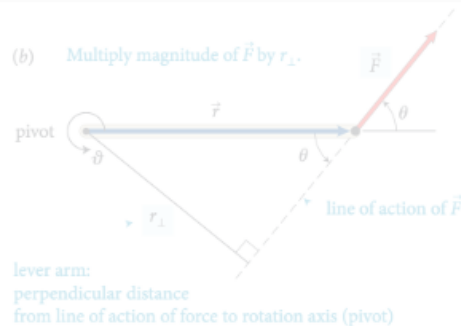
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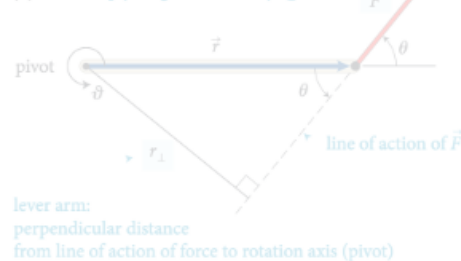
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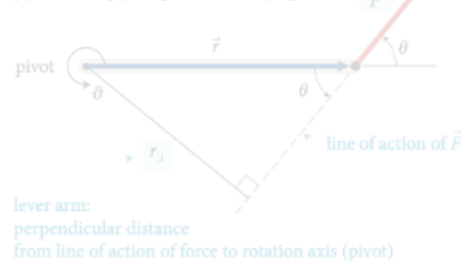
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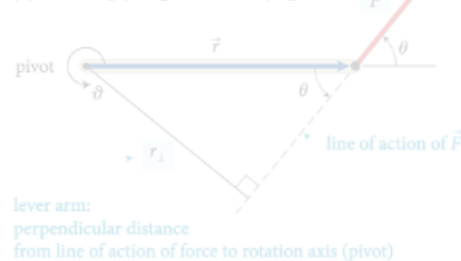
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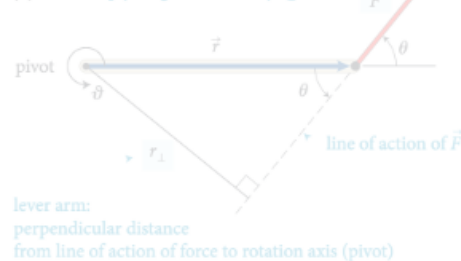
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Three forces are exerted on the lever of Figure 12.7. Forces  $\vec{F}_1$  and  $\vec{F}_2$  are equal in magnitude, and the magnitude of  $\vec{F}_3$  is half as great. Force  $\vec{F}_1$  is horizontal,  $\vec{F}_2$  and  $\vec{F}_3$  are vertical,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

- 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... before this wa... 2
- The extended free-body d... 4
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- (a) The change in rotationa...
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- Objects executing motion ar...
- Generally, for rotating bod... 2
- Does torque have the s... 3



action of the force and the perpendicular distance. So, the torque caused by a force  $F$  acting at a perpendicular distance  $d$  from a pivot is the product of the magnitude of the force and the perpendicular distance. It can be written as:

# Quality minimum

## timeliness (before class)

# • distribution (not cost)

The lever arm distances must now be determined relative to the left end of the rod. The lever arm distance for the force  $\vec{F}_1$  point is zero, and so the torque caused by the force about the left end of the rod is zero. If I choose the counterclockwise positive direction of rotation,  $\vec{F}_2$  causes a negative torque about the left end of the rod; the force  $\vec{F}_{PC}$  by the pivot causes a positive torque about the left end of the rod. The lever arm distance for  $\vec{F}_2$  at the left end of the rod is  $r_2$ , so that the torque  $\tau_2$  about the rod is at rest is the magnitude of the force  $F_2$  multiplied by  $r_2$  that is equal to the magnitude of the force  $F_2$  times  $r_2$ . The sign is negative. The sign for  $\vec{F}_{PC}$  is positive. The magnitude of the force  $F_{PC}$  is  $F_{PC}$ . The lever arm distance for  $\vec{F}_{PC}$  is  $r_{PC}$ . The result we obtain is the torque about the pivot, and the sum of

For the rod to be in static equilibrium, 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 is zero about any point. In general we can say that for an object in static equilibrium, the sum of the torques is zero.

# Conclusion

**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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as of this, t... 3

understandably partially w... 3

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The extended free-body diagram of the body is shown in Figure 10.10. The forces acting on the body are the weight  $W$ , the normal force  $N$ , the friction force  $f$ , and the applied force  $F$ . The weight  $W$  acts vertically downward from the center of the body. The normal force  $N$  acts vertically upward from the point of contact. The friction force  $f$  acts horizontally to the right from the point of contact. The applied force  $F$  acts horizontally to the left from the center of the body. The forces  $W$  and  $N$  are balanced, and the forces  $f$  and  $F$  are balanced. The net force on the body is zero, and the body is in equilibrium. The extended free-body diagram is a useful tool for analyzing the forces on a body in equilibrium. It allows us to see the forces acting on the body and to determine the conditions for equilibrium. In this case, the extended free-body diagram shows that the forces on the body are balanced, and the body is in equilibrium. This is consistent with the fact that the body is at rest. The extended free-body diagram is a useful tool for analyzing the forces on a body in equilibrium. It allows us to see the forces acting on the body and to determine the conditions for equilibrium. In this case, the extended free-body diagram shows that the forces on the body are balanced, and the body is in equilibrium. This is consistent with the fact that the body is at rest.

👉 This just means the net.

! I don't understand why ...

# Introduction

**11**

# Introduction

... ..



# 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 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  $\vec{F}_{pr}$  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  $r_1(F_1 + F_2) - (r_1 + r_2)F_2 = r_1F_1 - r_2F_2$ . 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. In general, for any stationary object, the sum of the torques is zero. For a stationary object we can choose any reference point we like to calculate torques. It pays to choose a reference point that simplifies the calculation. As you have seen, we do not need to consider any force that is exerted at the reference point. So, by putting the reference point at the point where a force is exerted, we can eliminate that force from the calculation.



**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)
- timeliness (before class)

- distribution (not clustered)

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

Enter your comment or question and press Enter

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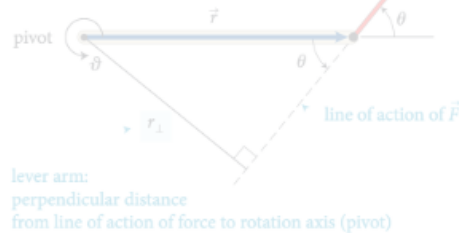
Objects executing motion ar...

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## rubric-based assessment

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



- quality (though future could be interpreted)

on of the force and the axis of rotation. The torque exerted on an object by a force is the product of the magnitude of the force and its lever arm.

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 right end.

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

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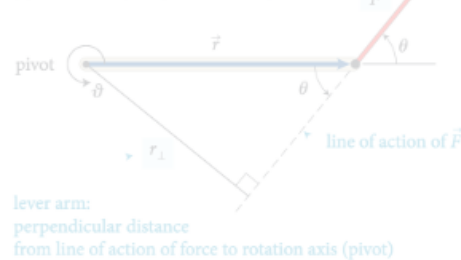
As we saw earlier in the chap...

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Does torque have the s...

## fully automated assessment

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

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

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

Oct 20 12:09 am

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

Oct 20 12:38 am

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

Oct 22 8:48 pm

Enter your comment or question and press Enter

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 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 one 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 to choose the pivot as a reference point because it is the point about which the object rotates. But 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  $45^\circ$  with the horizontal. Do these forces cause the lever to rotate about the pivot? If so, in which direction?

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Does torque have the s... 3



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# gradebook

## Gradebook

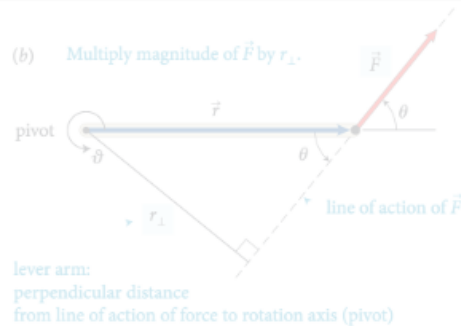
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		Total number of annotations			16
		Total number of annotations submitted on time			11
		Average quality of top 10 annotations submitted on time			1.80
		2 = demonstrates thorough and thoughtful reading and insightful interpretation of the reading, 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			



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  
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# connect pre-class and in-class activities

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Enter your comment or question and press Enter



## 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)

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

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

For a stationary object we can choose any reference point we like to 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  $45^\circ$  with the horizontal. Do these forces cause the lever to rotate about the pivot? If so, in which direction?

? I don't understand how this combination of factors tells you anything about direction? Aren't magnitude and lever arm distance both scalar quantities? It seems like we would need to know some sort of direction to calculate torque. Oct 20 12:09 am

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

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

Enter your comment or question and press Enter

On the very left, we see th...

It's interesting that the white ...

Is the reference frame i... 2

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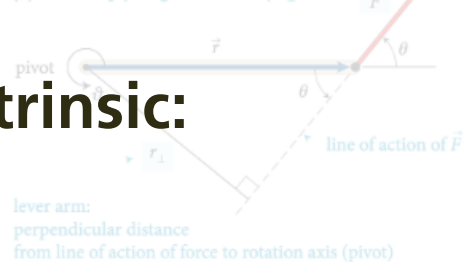
# motivating factors



## 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 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

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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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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



# 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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**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

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

I think you may be able to think about the direction separately. If you know 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, which is 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

# motivating factors

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

**Harvard student**

Perusall AP50 Fall 2015 » Chapter 12

Page 284 Eric Mazur

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

lever arm: perpendicular distance from the axis of rotation to the line of action of the force.

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  $\vec{F}_{\text{pt}}$  exerted by the pivot causes a positive torque about the left end of the rod. The lever arm distance of  $\vec{F}_2$  about the left end of the rod is  $r_1 + r_2$ ; that of  $\vec{F}_{\text{pt}}$  is  $r_1$ . The torque caused by  $\vec{F}_2$  is  $\tau_2 = -(r_1 + r_2)F_2$  and the torque caused by  $\vec{F}_{\text{pt}}$  is  $\tau_{\text{pt}} = r_1 F_{\text{pt}}$ . Taking into account the signs of the torques, we find that the sum of the torques about the left end of the rod is  $\tau_2 + \tau_{\text{pt}} = -(r_1 + r_2)F_2 + r_1 F_{\text{pt}}$ . This is the same result as before.

Exercise 12.1 shows that the sum of the torques about the right end of the rod is zero, just like the sum of the torques about the left end. You can choose any reference point, and each time you will find that the sum of the torques is zero. The reason is that the rod is not rotating about any point, and so the sum of the torques must be zero about any point. This is the principle of the lever.

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, since the lever arm distance for such a force is zero. This simplifies 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  $45^\circ$  with the horizontal. Do these forces cause the lever to rotate about the pivot? If so, in which direction?

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# motivating factors

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

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

Ohio State student

Perusall AP50 Fall 2015 » Chapter 12 Page 284 Eric Mazur

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

pivot  $\vec{r}$   $\theta$   $\vec{F}$   $\theta$  line of action of  $\vec{F}$   $r_{\perp}$

lever arm:  $r_{\perp}$  is the perpendicular distance from the pivot to the line of action of the force.

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  $\vec{F}_{\text{pt}}$  exerted by the pivot causes a positive torque about the left end of the rod. The lever arm distance of  $\vec{F}_{\text{pt}}$  about the left end of the rod is  $r_1 + r_2$  that of  $\vec{F}_2$  is  $r_2$ . 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 when we chose the right end of the rod as the reference point.

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 right end. This is a general result: for a stationary object, the sum of the torques is zero. The reason is that the rod is not rotating about any point, and so the sum of the torques must be zero about any point.

For a stationary object 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, for a stationary object, the sum of the torques is zero. For a stationary object, the sum of the torques 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  $45^\circ$  with the horizontal. Do these forces cause the lever to rotate about the pivot? If so, in which direction?

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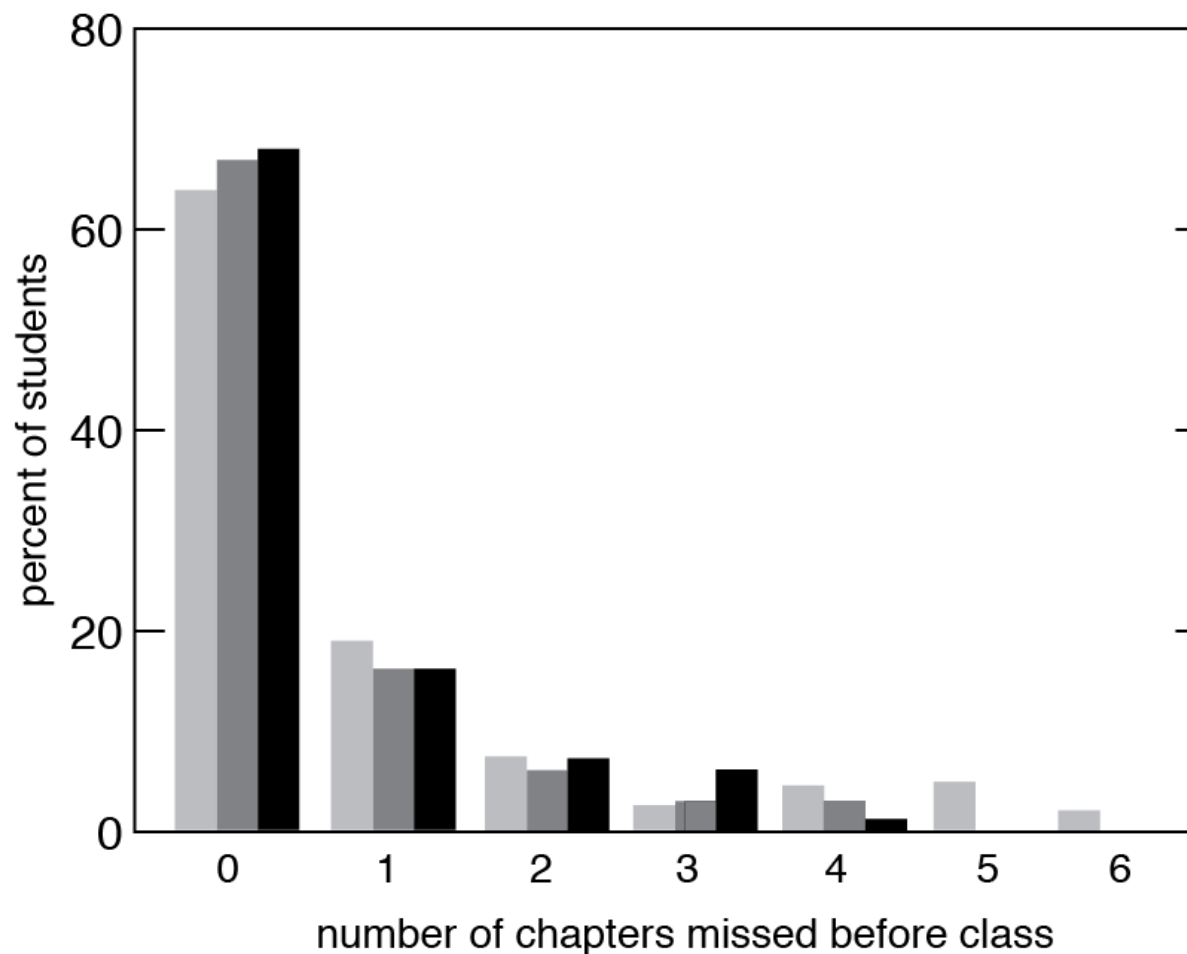
# class test results

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

$\vec{F}$

Reference point

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



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Page 284

Eric Mazur

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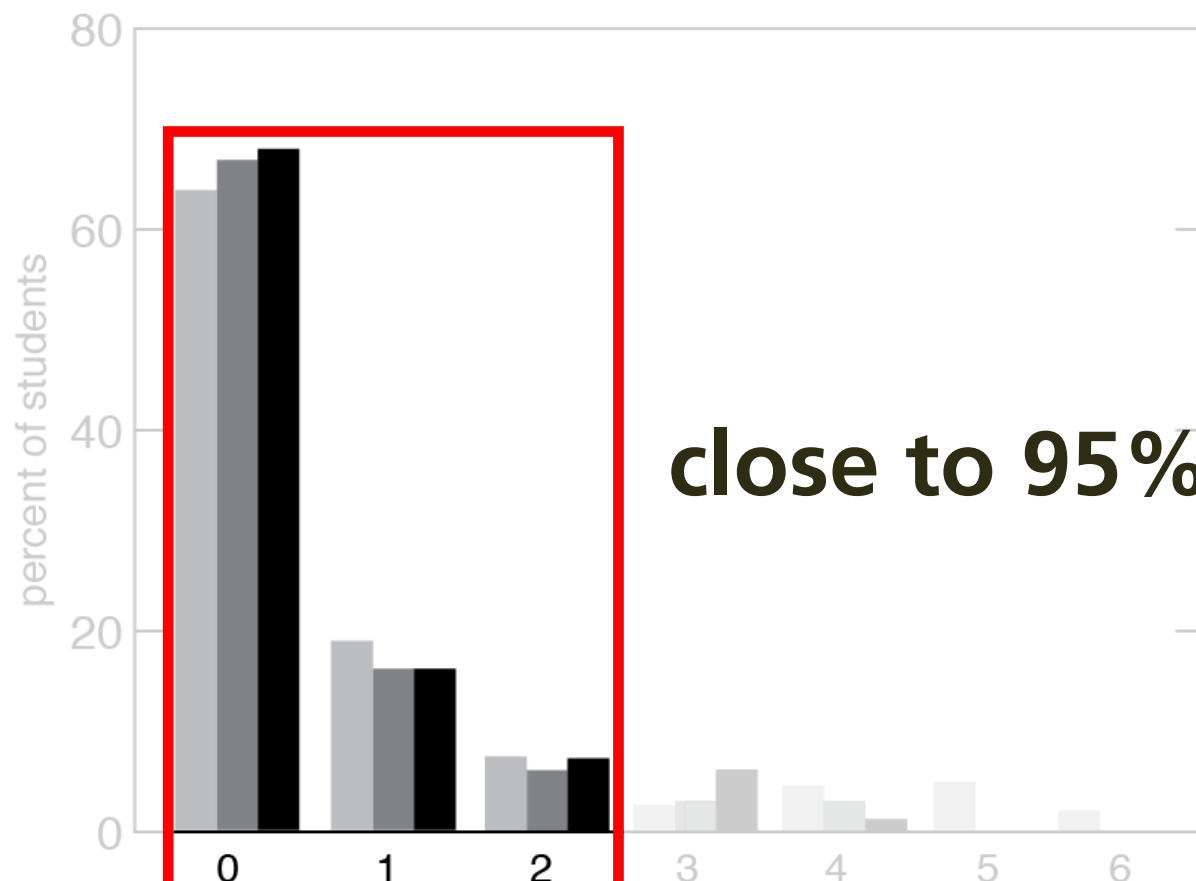
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close to 95%!

number of chapters missed before class

## 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  $45^\circ$  with the horizontal. Do these forces cause the lever to rotate about the pivot? If so, in which direction?

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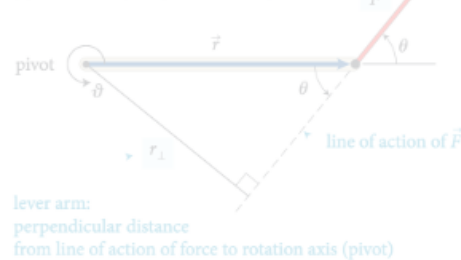
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## class test results

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

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

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

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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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every student prepared for every class

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

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

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

Enter your comment or question and press Enter



# additional research data

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

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



lever arm:  
perpendicular distance  
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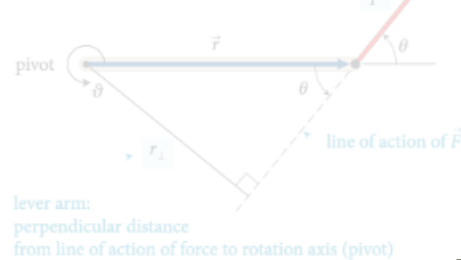
Enter your comment or question and press Enter

## additional research data

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

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Perusall AP50 Fall 2015 » Chapter 12: Rotational Motion and Angular Momentum

Page 284 Eric Mazur

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

For a stationary object we can choose any reference point to calculate the torques. If we choose the reference point at the point of application of a force, 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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(b) Multiply magnitude of  $\vec{F}$  by  $r_{\perp}$ .

lever arm:  
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- virtually 100% completion of assignments
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## CONCEPTS

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Like other rotational quantities, torque carries a sign that depends on the choice of direction for increasing  $\theta$ . In Figure 12.4, for example, the torque caused by  $\vec{F}_1$  about the pivot is positive, while 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).

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Consider a seesaw that is pivoted to 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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*all at no cost & without additional instructor effort!*



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**active engagement/social interaction a must!**

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