QuickStudy ACADEMIC

WORLD'S #1 ACADEMIC OUTLINE

PHYSICS

WHAT IS PHYSICS ALL ABOUT?

Physics seeks to understand the natural phenomena that occur in our universe; a description of a natural phenomenon uses many specific terms, definitions and mathematical equations.

Solving Problems in Physics
In physics, we use the **SI units (International System)** for data and calculations.

Base Quantity	Symbol	Unit
Length	L, x	Meter – m
Mass	m, M	Kilogram – kg
Temperature	T	Kelvin – K
Time	t	Second – s
Electric Current	I	Ampere – A (C/s)

Other physical quantities are derived from these basic units. **Prefixes** denote fractions or multiples of units; many variable symbols use **Greek** letters.
Math Skills: Many physical concepts are only understood with the use of **algebra, statistics, trigonometry** and **calculus**.

CLASSICAL MECHANICS

A. Classical or Newtonian Mechanics

The position of a body is given by an equation of motion with position, velocity and acceleration as variables; **mass** is the measure of the amount of matter; the standard unit for mass is kg. 1 kg = 1000 g; **inertia** is a property of matter, and as such, it occupies space.

1. Motion along a **straight line** is called **rectilinear**; the equation of motion describes the position of the particle and velocity for elapsed time, t
   a. **Velocity (v):** The rate of change of the displacement (x) with time (t): $v = \frac{dx}{dt} = \frac{\Delta x}{\Delta t}$
   b. **Acceleration (a):** The rate of change of the velocity with time: $a = \frac{dv}{dt} = \frac{\Delta v}{\Delta t}$
   c. **a & v** are vectors, with magnitude and direction
   d. **Speed** is the absolute value of the velocity; scalar with the **same units** as velocity

2. **Equations of Motion for One Dimension (1-D)**
   Equations of motion describe the future position (x) and velocity (v) of a body in terms of the initial velocity (v_0), position (x_0) and acceleration (a)
   a. For constant acceleration, the position is related to the time and acceleration by the following equation of motion: $x(t) = x_0 + v_0 t + \frac{1}{2} a t^2$
   b. For constant acceleration, the velocity vs. time is given by the following: $v(t) = v_0 + a t$
   c. If the acceleration is a function of time, the equation must be solved using $a = a(t)$

B. Motion in Two Dimensions (2-D)

1. For bodies moving along a **straight line**, derive x- and y-equations of motion
   $x = v_x t + \frac{1}{2} a_x t^2$
   $y = v_y t + \frac{1}{2} a_y t^2$
2. For a **rotating body**, use polar **coordinates**, an angle variable, θ, and r, a radial distance from the rotational center

Polar: (r, θ)
$x = r \cos\theta$
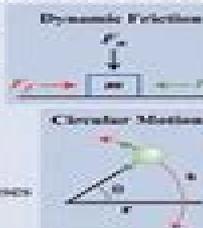$y = r \sin\theta$
$r^2 = x^2 + y^2$

C. Motion in Three Dimensions (3-D)

1. **Cartesian System:** Equations of motion with x, y and z components
2. **Spherical Coordinates:** Equations of motion based on two angles (θ and φ) and r, the radial distance from the origin

Spherical
$x = r \sin\theta \cos\phi$
$y = r \sin\theta \sin\phi$
$z = r \cos\theta$
$r^2 = x^2 + y^2 + z^2$

D. Newton's Laws of Motion

Newton's Laws are the core principles for describing the motion of classical objects in response to forces. The SI unit of force is the **Newton, N;** $1N = 1kg \cdot m/s^2$; the cgs unit is the **dyne;** 1 dyne = 1g cm/s²

1. **Newton's 1st Law:** A body remains at rest or in motion unless influenced by a force
2. **Newton's 2nd Law:** Force and acceleration determine the motion of a body and predict future position and velocity: $\mathbf{F} = m\mathbf{a}$ OR $\sum \mathbf{F} = m\mathbf{a}$
3. **Newton's 3rd Law:** Every action is countered by an opposing action

E. Types of Forces

1. A **body force** acts on the entire body, with the force acting at the center of mass
   a. A gravitational force, F_g, pulls an object toward the center of the Earth: $\mathbf{F_g} = m\mathbf{g}$
   b. **Weight** = F_g; gravitational force
   c. **Mass** is a measure of the quantity of material, independent of g and other forces
2. **Surface forces** act on the body's surface
   a. **Friction**, F_f, is proportional to the force normal to the part of the body in contact with a surface. $F_f = F_n = \mu F_n$
      i. **Static friction** resists the movement of a body
      ii. **Dynamic friction** slows the motion of a body
      For an object on a **horizontal plane:**
      $F_f = \mu F_n = \mu m g$
      Net force = $F_a - F_f$
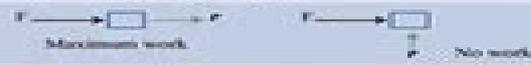
Dynamic Friction

Circular Motion

F. Circular Motion

1. Motion along a circular path uses polar coordinates: (r, θ)
2. Key Variables:

r	Meter	The distance from the rotation center (center of mass)
θ	Radian	The angle between r and the (x) axis
ω	Radian/second	The angular velocity
α	Radian/second²	The angular acceleration
s	Meter	The circular motion arc is $s = r\theta$ (θ in rad)

3. **Tangential** acceleration & velocity:
   $v_t = r\omega$, $a_t = r\alpha$; v and a along the path of the motion arc
4. **Centripetal** acceleration $a_c = \frac{v^2}{r}$; a is directed toward the rotational center
   a. The centripetal force keeps the body in circular motion with a tangential acceleration and velocity

G. Kinetic Energy & Work

1. **Kinetic energy, K:** Kinetic energy is the energy of motion; mass, **m** and velocity, v; $K = \frac{1}{2} m v^2$
   The SI energy unit is the **Joule** (J):
   $1J = 1 \text{ kg m}^2/\text{s}^2$
2. **Momentum, p:** Momentum is a property of motion, defined as the product of mass and velocity: $\mathbf{p} = m\mathbf{v}$
3. **Work (W):** Work is a force acting on a body moving a distance; for a general force, F, and a body moving a path, s: $W = \int \mathbf{F} \cdot d\mathbf{s}$
   For a **constant force**, work is the scalar product of the two vectors: force, F, and path, r:
   $W = \mathbf{F} \cdot \mathbf{d} \cos(\theta) = \mathbf{F} \cdot \mathbf{r}$

Maximum work   No work

4. **Power (P)** is energy expended per unit time:
   $P = \frac{\Delta \text{Work}}{\Delta \text{time}} = \frac{\Delta \text{Work}}{\Delta t}$
   $\text{Work} = \int P(t) dt$
   The SI unit for power is the **Watt (W):**
   $1 W = 1 \text{ Joule/second} = 1 \text{ J/s}$
   Work for a **constant output of power:**
   $W = P \cdot \Delta t$

H. Potential Energy & Energy Conservation

1. The total energy of a body, E, is the sum of kinetic, K, & potential energy, U: $E = K + \sum U$
2. **Potential energy** arises from the interaction with a potential from an external force
   Potential energy is energy of position; U(r); the form of U depends on the force generating the potential:
   Gravitation: $U(h) = mgh$
   Electrostatic: $U(r_{12}) = \frac{q_1 q_2}{r_{12}}$
   If there are no other forces acting on the system, E is constant and the system is called **conservative**

I. Collisions & Linear Momentum

1. **Types of Collisions**
   a. **Elastic:** conserve energy
   b. **Inelastic:** energy is lost as heat or deformation
2. **Relative Motion & Frames of Reference:** A body moves with velocity v in frame S; in frame S' the velocity is v'; if v_s' is the velocity of frame S' relative to S, therefore: $\mathbf{v} = \mathbf{v_s'} + \mathbf{v'}$
3. **Elastic Collision**
   Conserve Kinetic Energy: $\sum \frac{1}{2} m_i v_i^2 = \sum \frac{1}{2} m_i v_i'^2$
   Conserve Momentum: $\sum m_i v_i = \sum m_i v_i'$
4. **Impulse** is a force acting over a time
   $\text{Impulse} = F \cdot \Delta t$ or $\int F(t) dt$
   Impulse is also the **momentum change:** $p_{final} - p_{initial}$

Collisions

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Ira Remsen

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