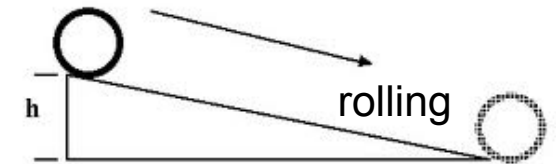




# University Physics 226N/231N Old Dominion University Rotational Motion



Dr. Todd Satogata (ODU/Jefferson Lab)  
satogata@jlab.org

<http://www.toddsatogata.net/2012-ODU>

Monday October 22, 2012

Happy Birthday to Clinton Davison (1937 Nobel), Franz Liszt, Ichiro Suzuki, Spike Jonze, and Plan B!

Happy Fechner Day, Used Car Day, and National Nut Day!



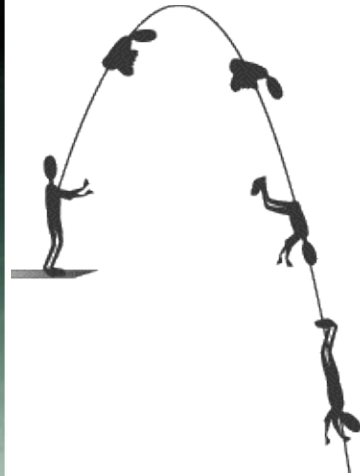
Jefferson Lab

Prof. Satogata / Fall 2012

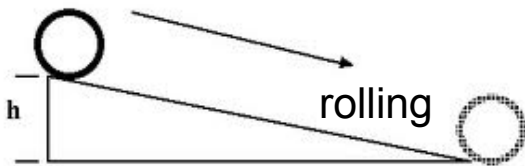
ODU University Physics 226N/231N 1



# This Week: Rotational Motion



- Describe the rotational motion of rigid bodies
  - We'll develop an analogy between new quantities describing rotational motion and familiar quantities from one-dimensional linear kinematics
- Calculate the rotational inertias of objects made of discrete and continuous distributions of matter
  - Rotational inertia is the rotational analog of mass
  - Gyroscopes!!
- We'll start to handle more interesting problems involving both linear and rotational motion
- We'll describe rolling motion



# Quick One-Dimensional Kinematics Review

- We're going to draw explicit analogies between angular motion quantities and our old friends **position**, **velocity**, and **acceleration** from one-dimensional kinematics
- Time for a bit of review
  - Definitions of velocity and acceleration

$$\text{velocity } v \equiv \frac{dx}{dt}$$

$$\text{acceleration } a \equiv \frac{dv}{dt}$$

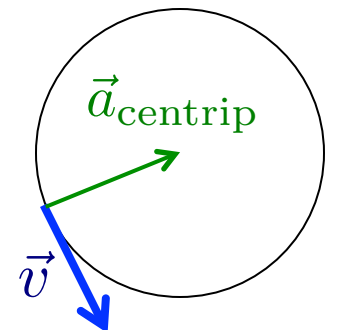
- Constant acceleration motion

$$x - x_0 = v_0 t + \frac{1}{2} a t^2$$

$$v = v_0 + a t$$

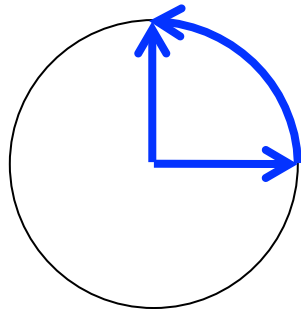
- Centripetal acceleration related to tangential velocity

$$a_{\text{centrip}} = \frac{v^2}{r}$$

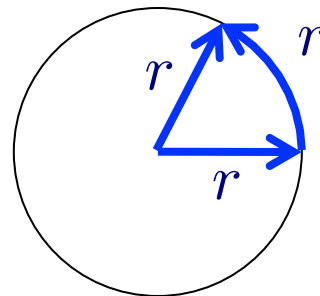


# Angular Position

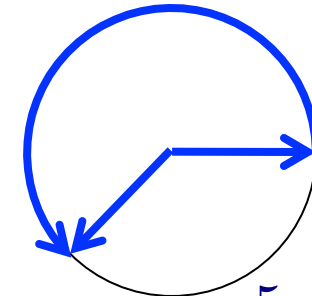
- What do we use for position in angular motion problems?
  - The angle that an object is from a reference angle  $\theta = 0$
  - The sign convention is **usually that clockwise is positive**
  - The  $\theta = 0$  location, like  $x=0$ , is usually defined by the problem
    - We care more about **angular distances**,  $\Delta\theta = \theta(t_2) - \theta(t_1)$
  - We also always use **radians** where  $2\pi \text{ rad} = 360^\circ$ 
    - 1 rad is the angle where the arc length is equal to the circle radius



$$\Delta\theta = 90^\circ = \frac{\pi}{2} \text{ rad}$$



$$\Delta\theta = 57.3^\circ = 1 \text{ rad}$$



$$\Delta\theta = 225^\circ = \frac{5\pi}{4} \text{ rad}$$

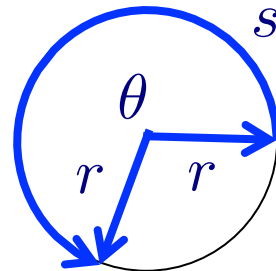
- A conversion example:  $225^\circ \left( \frac{2\pi \text{ rad}}{360^\circ} \right) = \frac{5}{8}(2\pi) \text{ rad} = \frac{5\pi}{4} \text{ rad}$



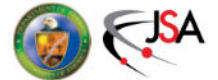
# Angular Position: Importance of Radians

- That radians thing? Yeah, that's important...
  - If we write angles in radians, we can write a **tremendously useful equation** that relates the actual distance around the arc  $s$  to angles and radii:

$$s = r\theta$$



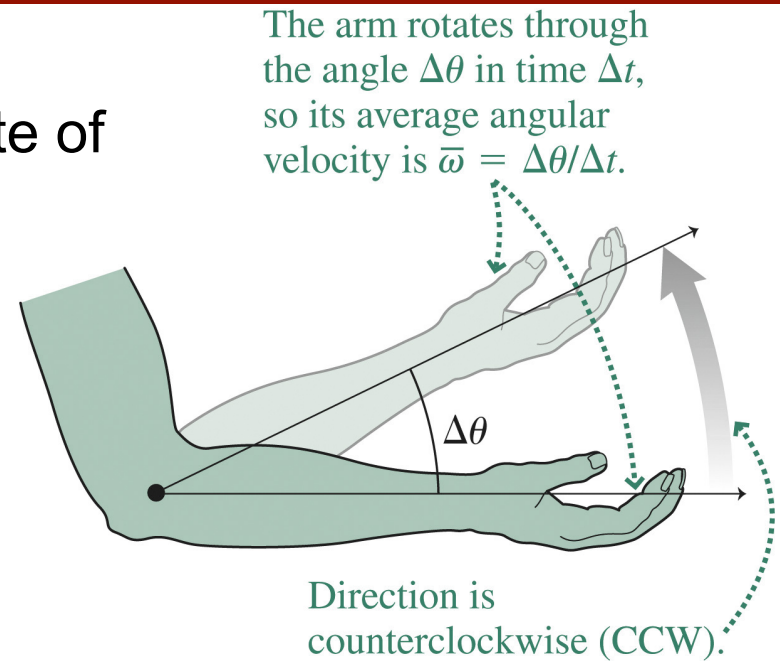
- Here  $s$  is the distance around the arc. This formula lets us switch between real distances (like  $s$  and  $r$ , which are in distance units like meters) and angular distances (which are in radians)
- Example:  $\theta = 30^\circ = \frac{\pi}{6}$  rad,  $r = 2$  m  $\Rightarrow s = \frac{\pi}{3}$  m  $\approx 1.05$  m
- **Warning:** This equation (and most others we'll derive from now on) only work if the angle  $\theta$  is in radians!
  - Since a radian is a ratio, it really is technically “dimensionless”



# Angular Velocity

- Angular velocity  $\omega$  [rad/s] is the rate of change of angular position with time

$$\text{Average : } \bar{\omega} \equiv \frac{\Delta\theta}{\Delta t}$$
$$\text{Instantaneous : } \omega \equiv \frac{d\theta}{dt}$$



- Angular velocity  $\omega$  is related to linear velocity  $v$  at a particular radius  $r$  from the rotation axis

$$v = \omega r$$

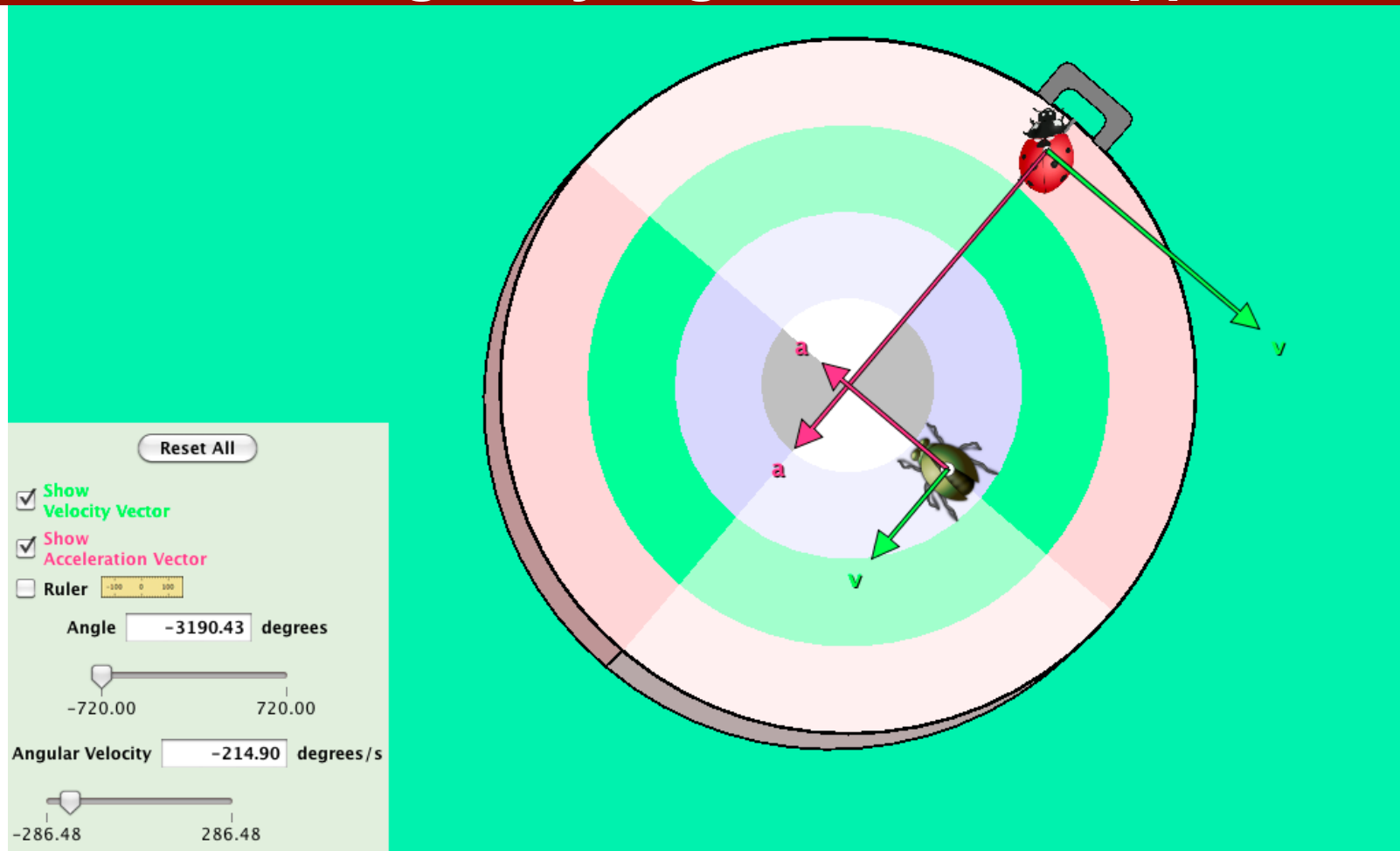
**Warning: This is only true if the angular velocity distance units are radians!!!**



all radii rotate at 45 rpm but different  $v$ !



# Revisiting Ladybug Revolution Applet



- <http://phet.colorado.edu/en/simulation/rotation>
- See differences in magnitudes **and** directions of **linear velocity and centripetal acceleration**
- Click on the “Rotation” tab



# Revisiting Ladybug Revolution

**Angular Velocity**

$\omega = 2.00$

Go! Clear

**Velocity**

Show speed  
 Show X-Velocity  
 Show Y-Velocity

Show graphs:

$\theta, \omega, x \text{ \& \ } y$   
  $\theta, \omega, \alpha$   
  $\theta, \omega, v$   
  $\theta, \omega, a$

Symbol Key

Show Platform Graph  
 Show Ladybug Graph  
 Show Beetle Graph

Angle Units

degrees  
 radians

Show Velocity Vector  
 Show Acceleration Vector

Reset All

Ruler

Sim Speed: slow ————— fast

Go! Playback Step Rewind Clear

**Angular Velocity (rad/s) vs time (s)**

Time (s)	Angular Velocity (rad/s)
0 - 4	0
4 - 12.5	2.00
12.5 - 20	2.00

$\omega_{\text{platform}} = 2.00 \text{ rad/s}$   
 $\omega_{\text{ladybug}} = 2.00 \text{ rad/s}$   
 $\omega_{\text{beetle}} = 2.00 \text{ rad/s}$

**Velocity (m/s) vs time (s)**

Time (s)	Ladybug Velocity (m/s)	Beetle Velocity (m/s)
0 - 4	0	0
4 - 12.5	4.00	7.50
12.5 - 20	4.00	7.50

$|v|_{\text{ladybug}} = 4.00 \text{ m/s}$   
 $|v|_{\text{beetle}} = 7.50 \text{ m/s}$



## Revisit an old Ponderable (10 minutes)

- Todd gets nostalgic and spins up his old **45 RPM** (revolutions per minute) record collection. Each record has a **7 inch total diameter**.
  - How fast is the outermost edge of the album moving in inches/sec?
  - How many “gees” of acceleration does a bug on the edge feel? ( $g=32 \text{ feet/s}^2=384 \text{ inches/s}^2$ )



"NO DOUBT ABOUT IT—HIS HEARING'S GETTING WORSE."



# Angular Acceleration

- Angular acceleration  $\alpha$  [rad/s<sup>2</sup>] is the rate of change of angular velocity with time

$$\text{Average : } \bar{\alpha} \equiv \frac{\Delta\omega}{\Delta t}$$

$$\text{Instantaneous : } \alpha \equiv \frac{d\omega}{dt}$$

- Angular acceleration  $\alpha$  is related to **tangential** linear acceleration  $a_t$  at a particular radius  $r$  from the rotation axis

$$a_t = \alpha r$$

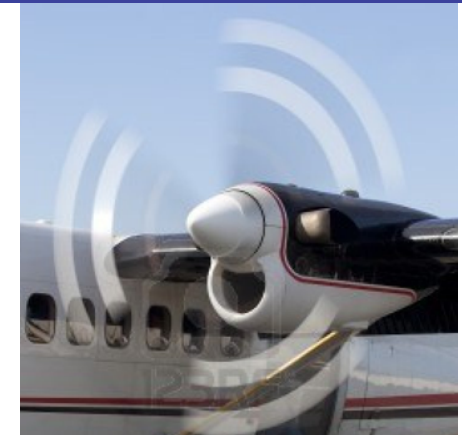
Recall there is also centripetal (radial) acceleration

$$a_r = a_{\text{centrip}} = \frac{v^2}{r} = \omega^2 r$$



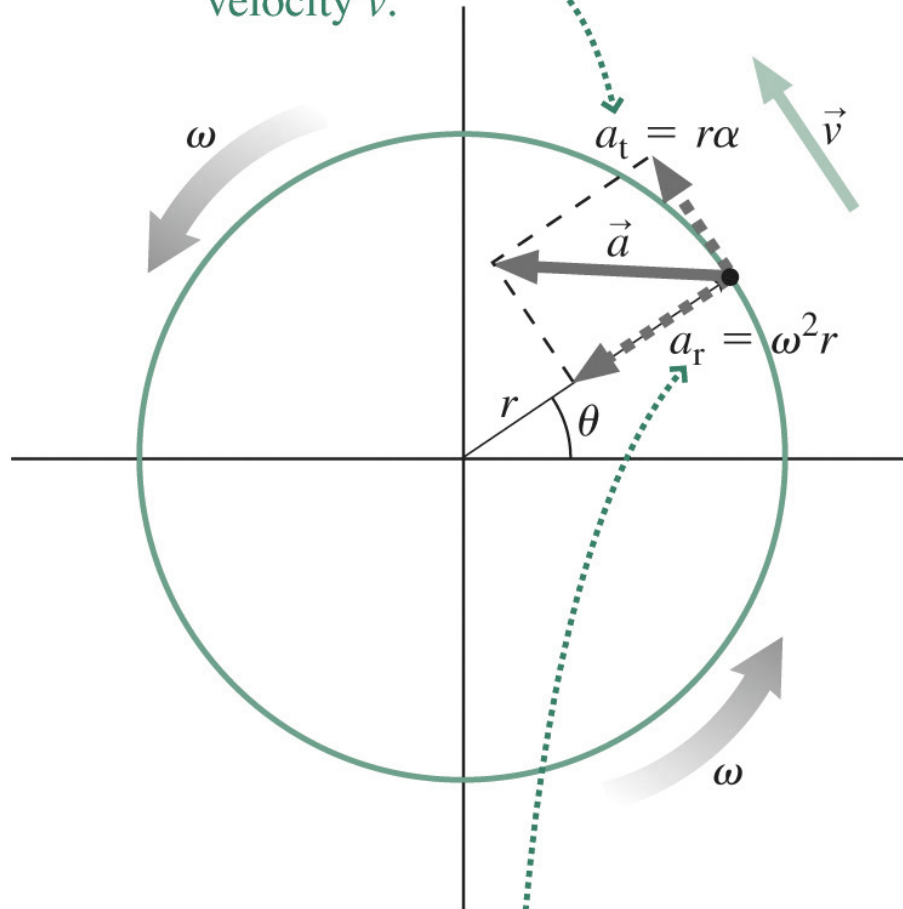
Think of an amusement park ride or propeller or engine spinning up – or spinning down.

That's angular acceleration.



# Angular Acceleration Picture (from text)

$a_t$  is the tangential component of acceleration  $\vec{a}$  and is parallel to the linear velocity  $\vec{v}$ .



$$a_t = \alpha r$$

$$a_r = a_{\text{centrip}} = \frac{v^2}{r} = \omega^2 r$$

$a_r$  is the radial component, perpendicular to  $\vec{v}$ .



# Constant Angular Acceleration

- Problems with constant angular acceleration are exactly analogous to similar problems involving linear motion in one dimension.
  - The **exact** same equations apply, with  $x \rightarrow \theta$ ,  $v \rightarrow \omega$ ,  $a \rightarrow \alpha$

**Table 10.1** Angular and Linear Position, Velocity, and Acceleration

Linear Quantity	Angular Quantity
Position $x$	Angular position $\theta$
Velocity $v = \frac{dx}{dt}$	Angular velocity $\omega = \frac{d\theta}{dt}$
Acceleration $a = \frac{dv}{dt} = \frac{d^2x}{dt^2}$	Angular acceleration $\alpha = \frac{d\omega}{dt} = \frac{d^2\theta}{dt^2}$

## Equations for Constant Linear Acceleration

$$\bar{v} = \frac{1}{2}(v_0 + v) \quad (2.8)$$

$$v = v_0 + at \quad (2.7)$$

$$x = x_0 + v_0t + \frac{1}{2}at^2 \quad (2.10)$$

$$v^2 = v_0^2 + 2a(x - x_0) \quad (2.11)$$

## Equations for Constant Angular Acceleration

$$\bar{\omega} = \frac{1}{2}(\omega_0 + \omega) \quad (10.6)$$

$$\omega = \omega_0 + \alpha t \quad (10.7)$$

$$\theta = \theta_0 + \omega_0t + \frac{1}{2}\alpha t^2 \quad (10.8)$$

$$\omega^2 = \omega_0^2 + 2\alpha(\theta - \theta_0) \quad (10.9)$$



© 2012 Pearson Education, Inc.



## Example Problem

- A record on a turntable is accelerated from rest to an angular velocity of 33.3 revolutions/minute in 2 secs. Find the average angular acceleration.



- Solution: The initial angular velocity is zero.

$$\omega_0 = 0 \text{ rad/s}$$

The final angular velocity is

$$\omega = (33 \text{ rev/min}) \left( \frac{1 \text{ min}}{60 \text{ s}} \right) \left( \frac{2\pi \text{ rad}}{1 \text{ rev}} \right) = 3.46 \text{ rad/s}$$

Then we have

$$\bar{\alpha} = \frac{\Delta\omega}{\Delta t} = \frac{\omega - \omega_0}{\Delta t} = \frac{3.46 \text{ rad/s}}{2 \text{ s}} = 1.73 \text{ rad/s}^2$$



## Example Problem 2

- A fan is started from rest and after 5.0 s has reached its maximum rotational velocity of 60 rad/s. Find the average angular acceleration and how many revolutions the fan makes while accelerating, assuming constant acceleration.

Solution:

$$\begin{aligned}\omega_0 &= 0 \text{ rad/s} \\ \omega &= 60 \text{ rad/s} \\ \Delta t &= 5.0 \text{ s}\end{aligned}$$

$$\bar{\alpha} = \frac{\Delta\omega}{\Delta t} = \frac{\omega - \omega_0}{\Delta t} = \frac{60 \text{ rad/s}}{5.0 \text{ s}} = 12 \text{ rad/s}^2$$

$$\Delta\theta = \omega_0 t + \frac{1}{2} \alpha t^2 = \frac{1}{2} \alpha t^2 \quad \text{like } \Delta x = v_0 t + \frac{1}{2} a t^2$$

$$\Delta\theta = \frac{1}{2} (12 \text{ rad/s}^2) (5.0 \text{ s})^2 = 150 \text{ rad}$$

or converting to revolutions:

$$\Delta\theta = 150 \text{ rad} \left( \frac{1 \text{ rev}}{2\pi \text{ rad}} \right) = 23.9 \text{ revolutions}$$



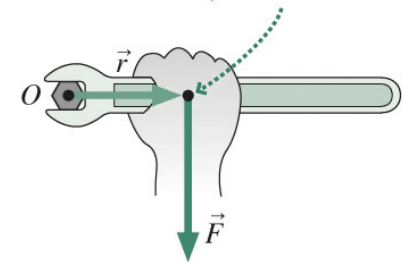
# Torque

- Torque  $\tau$  is the rotational analog of force, and results from the application of one or more forces.
- Torque is relative to a chosen rotation axis.
- Torque depends on:
  - the distance from the rotation axis to the force application point.
  - the magnitude of the force  $\vec{F}$
  - the orientation of the force relative to the displacement  $\vec{r}$  from axis to force application point:

$$\vec{\tau} = \vec{r} \times \vec{F} \quad \tau = rF \sin \theta$$

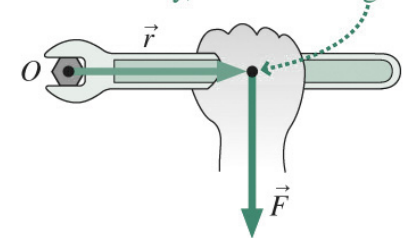
The same force is applied at different points on the wrench.

Closest to  $O$ ,  $\tau$  is smallest.



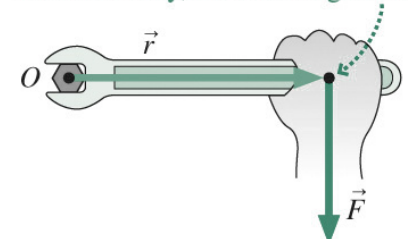
(a)

Farther away,  $\tau$  becomes larger.



(b)

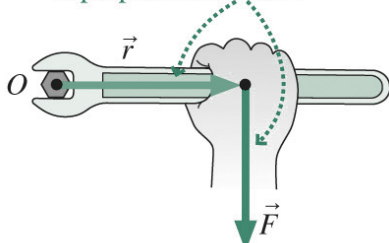
Farthest away,  $\tau$  becomes greatest.



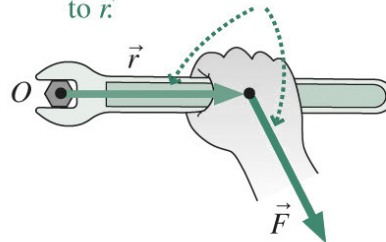
(c)

The same force is applied at different angles.

Torque is greatest when  $\vec{F}$  is perpendicular to  $\vec{r}$ .



Torque decreases when  $\vec{F}$  is no longer perpendicular to  $\vec{r}$ .



Torque is zero when  $\vec{F}$  is parallel to  $\vec{r}$ .

