

# N. L. M.

PAGE NO.:

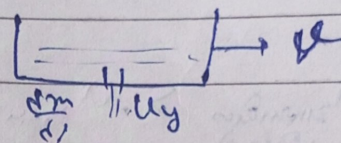
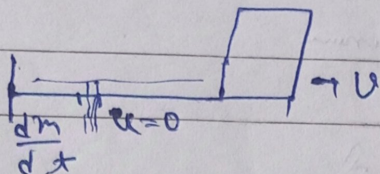
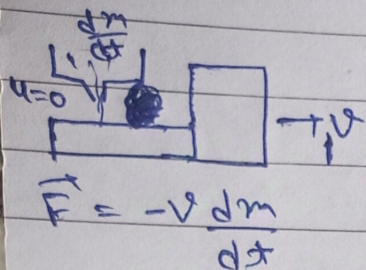
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$$\vec{P} = m\vec{v}$$

$$\vec{F} = \frac{d\vec{P}}{dt}$$

$$\vec{F} = m \frac{d\vec{v}}{dt} + \vec{v} \cdot \frac{dm}{dt} \quad m = \text{const}$$

$$\vec{F} = m \frac{d\vec{v}}{dt} = m\vec{a}$$



$$V_{\text{rel}} = V_{\text{rel}} - V_{\text{rel}} = 0$$

$$\vec{F}_{\text{rel}} = -u_y \frac{dm}{dt} \hat{j}$$

$$\frac{dm}{dt} = -v_e \hat{e} \quad \vec{F} = v_e \hat{e}$$

2nd case: mass is moving to the right

$$F = \rho A v^2$$

2nd case: mass is moving to the left

$$F_{\text{thrust}} = v \frac{dm}{dt}$$

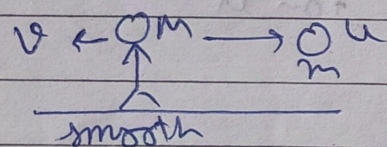
$$v = \text{distance} / \text{time}$$

$$F_{\text{net}} = F_{\text{th}} - mg \quad a = \frac{v \frac{dm}{dt} - mg}{m}$$

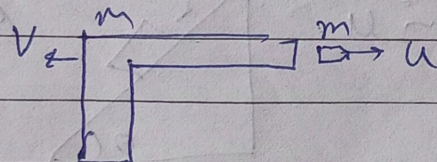
3rd case

$$I = \Delta P$$

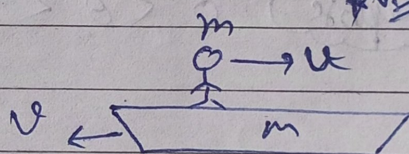
2nd case: mass is moving to the right



$$v = -\frac{mu}{m}$$

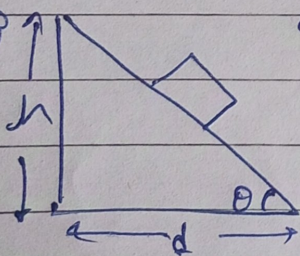


$$v = -\frac{mu}{m}$$



$$v_{\text{rel}} = \frac{mu}{m+m}$$

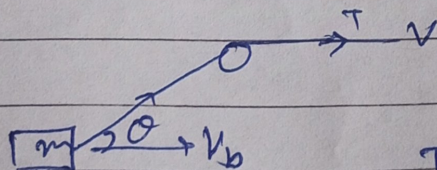
4th case



$$v = \sqrt{2gh}$$

$$t = \sqrt{\frac{2s}{a}} = \frac{1}{\sin \theta} \sqrt{\frac{2h}{g}}$$

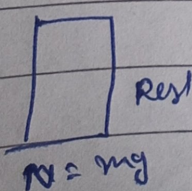
5th case: mass is moving to the right



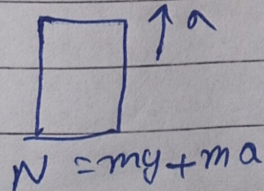
$$T.V_b \cos \theta + T.V \cos 180 = 0$$

$$T.V_b \cos \theta + T.V \cos 180 = 0$$

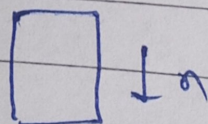
6th case: mass is moving to the left



$$N = mg$$



$$N = mg + ma$$



$$N = mg - ma$$



$$f_s \text{ static} = F_{\text{ext/applied}}$$

$$f_s = \mu_s N$$

↑  
maximum

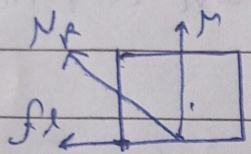
$$f_k \text{ kinetic} = f_s = \mu_k N$$

↑  
const.

$$\mu_{\text{static}} > \mu_{\text{static}} > \mu_{\text{kinetic}}$$

static friction

$$f_{\text{static}} > f_{\text{static}} > f_{\text{kinetic}}$$

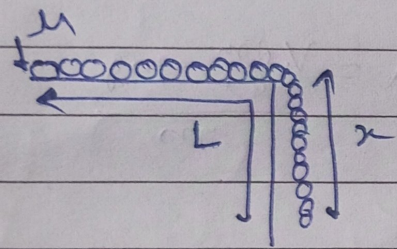


$$N_{\text{min}} = mg$$

$$N_{\text{max}} = mg \sqrt{1 + \mu^2}$$

$f_{\text{min}}$  static

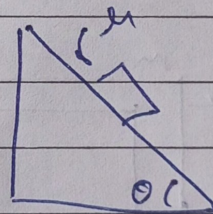
$$f_{\text{min}} = \frac{\mu mg}{\sqrt{1 + \mu^2}}$$



static friction is always present

$$\frac{x}{L} = \frac{\mu}{1 + \mu}$$

Angle of Repose  $0 < \theta < \tan^{-1} \mu$



$$\theta = \tan^{-1} \mu$$