

# **Grade 12 Physics**

SPH4U

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# Contents

<b>1</b>	<b>Unit 1A</b>	<b>3</b>
1.1	Review of Describing and Graphing Motion . . . . .	3
1.1.1	Position: $\vec{d}$ . . . . .	3
1.1.2	displacement: $\Delta\vec{d}$ . . . . .	3
1.1.3	Velocity: $\vec{v}$ . . . . .	3
1.1.4	Acceleration: $\vec{a}$ . . . . .	3
1.1.5	Graphing motion . . . . .	3
1.2	Equations of Motion . . . . .	5
1.2.1	Format requirements for answering Motion questionss . . . . .	5
1.3	Adding and Subtracting 2-Dimensional Vectors . . . . .	6
1.3.1	Vector addition and subtraction key words . . . . .	6
1.3.2	Steps for solving a vector problem . . . . .	6
1.3.3	Another question type . . . . .	6
1.4	Frame of Reference . . . . .	7
1.4.1	1 Dimension Frame of Reference . . . . .	7
1.5	Relative Velocities in Two Dimensions . . . . .	9
1.5.1	Recall . . . . .	9
1.5.2	Definition . . . . .	9
1.6	F.O.R in 2-D . . . . .	10
1.7	Review of Netwon's Laws of Montion . . . . .	11
1.7.1	Netwon's First Laws . . . . .	11
1.7.2	Newton's second Law . . . . .	11
1.7.3	Newton's Third Law . . . . .	11
1.7.4	Free Body Diagrams (FBD) . . . . .	12
1.7.5	Application of Newton's second Law . . . . .	12
1.8	Review of Projectile Motion . . . . .	13
1.8.1	basic . . . . .	13
1.8.2	Special formula . . . . .	13
1.8.3	An example question . . . . .	14
1.9	Friction . . . . .	15
1.9.1	Kinetic Friction . . . . .	15
1.9.2	Static Friction . . . . .	15
1.9.3	Remainder . . . . .	15
1.10	Tension, compression and Pulleys . . . . .	17
1.10.1	Tention: T . . . . .	17
1.10.2	Compression: C . . . . .	17
1.11	Inclined plane with Friction . . . . .	18
1.11.1	How to determine the direction that the system will likely to accelerate . . . . .	18
1.11.2	Example template . . . . .	18

<b>2</b>	<b>Unit 1B</b>	<b>19</b>
2.1	Proportionality . . . . .	19
2.2	Fictitious Forces and Apparent Weight . . . . .	21
2.2.1	Compare Inertial and non-inertial F.O.R . . . . .	21
2.2.2	Fictitious Forces . . . . .	21
2.2.3	Apparent Weight . . . . .	21
2.2.4	Some of the formulas . . . . .	21
2.3	Lecture 2.5 . . . . .	22
2.3.1	Uniform Circular Motion . . . . .	22
2.3.2	Centripetal acceleration . . . . .	22
2.3.3	Formulas . . . . .	22
2.4	Motion of a car on Banked Turn . . . . .	23
2.4.1	Forces . . . . .	23
2.4.2	Critical Speed . . . . .	23
2.5	Universal Gravitation, Gravitational field . . . . .	24
2.5.1	Force of Gravity . . . . .	24
2.5.2	Gravational Fields . . . . .	24
2.5.3	Differences between strength of gravity and acceleration . . . . .	24
2.6	Satellites . . . . .	26
2.6.1	Newton's Cannon . . . . .	26
2.6.2	Geosynchronous . . . . .	26
2.6.3	Formulas related to satellite . . . . .	26
2.7	Rotating Frame of Reference . . . . .	28
2.7.1	Little problem . . . . .	28
2.7.2	Perceived Acceleration in a Rotating Frame of Reference . . . . .	29
<b>3</b>	<b>Unit 2: Energy and Momentum</b>	<b>31</b>
3.1	Work and Kinetic Energy . . . . .	31
3.1.1	Kinetic Energy . . . . .	31
3.1.2	Mechanical Work . . . . .	31
3.2	Gravitational Potential Energy . . . . .	33
3.2.1	Some boring definitions . . . . .	33
3.2.2	Formulas for GPE . . . . .	33
3.3	The law of the Conservation of Energy . . . . .	34
3.3.1	Boring Definitions . . . . .	34
3.3.2	Question solving techniques . . . . .	34
3.4	String & Elastic Potential Energy . . . . .	35
3.4.1	The Force of String . . . . .	35
3.4.2	Elastic Potential Energy . . . . .	35
3.4.3	Ignore Gravitational Potential Energy . . . . .	36
3.5	Simple Harmonic Motion . . . . .	37
3.5.1	Definitions . . . . .	37
3.5.2	How can we solve for the acceleration of SHM . . . . .	38
3.5.3	The period of the Simple Harmonic Motion . . . . .	39
3.6	Linear Momentum & Impulse . . . . .	40
3.7	Conservation of Momentum . . . . .	41
3.7.1	Equation . . . . .	41
3.8	Types of Collisions . . . . .	43
3.8.1	Definitions . . . . .	43
3.8.2	Elastic Collisions . . . . .	43
3.8.3	Inelastic Collision . . . . .	44
3.9	HEAD-ON Collisions . . . . .	45
3.9.1	Equations . . . . .	45

# Chapter 3

## Unit 2: Energy and Momentum

### 3.1 Work and Kinetic Energy

#### 3.1.1 Kinetic Energy

**Definition 3.1.1.** *Kinetic energy is the energy of **motion**. There are two types of kinetic energy*

##### Type 1: Translational Kinetic Energy

The kinetic energy that an object has because it is *moving from one location to another*. It can be described by this formula:

$$E_k = \frac{1}{2}mv^2 \quad (3.1)$$

$E_k$  is the translational kinetic energy of the object (in  $J$  or  $kgm^2/s^2$ )

$m$  is the mass in  $kg$

$v$  is the speed in  $m/s$

Because all motion is relative, an object's speed (and therefore  $E_k$ ) *depends on the chosen Frame of Reference*

**Notes:**

Do not solve the conservation of energy problem involving a change of Frame of Reference. Start from your perspective

$E_k$  is a scalar, not a vector

##### Type 2: Rotational Kinetic Energy

Not testable, don't give a shit about this question.

#### 3.1.2 Mechanical Work

**Definition 3.1.2.** *Mechanical work: Transfer of energy into  $E_k$  or the transfer of kinetic energy into another type of energy*

**Definition 3.1.3.** *Potential energy: Energy which is stored in a system of objects due to forces acting in between those objects*

The formula to describe the work is:

$$W = F_{A/B} * \Delta \vec{d}_B * \cos\theta \quad (3.2)$$

$W_{A/B}$  is the work that  $F_{A/B}$  does on the object  $B$ . This is also the amount of  $E_k$  that object A transfers into object B when A exerts a force on B(in J)  
 $F_{A/B}$  is the magnitude of force that A exerts on B(in J)  
 $\theta$  is the angle between  $F_{A/B}$  and  $B$ 's displacement

Remainder: Only forces on the direction of displacement is responsible for the work

## 3.2 Gravational Potential Energy

### 3.2.1 Some boring definitions

**Definition 3.2.1.** (*Gravational Potential Energy*): The energy stored in a system of objects due to the force of gravity acting between those objects. In other words, the energy is stored collectively **among all** the objects in the system

When the force of gravity acting on the two objects causes this stored GPE to be converted into kinetic energy, the kinetic energy is not **shared evenly** between these two objects. In the class Example, the earth effectively gets **zero** and the car effectively gets **all of them**. Due to this reason, when we have two objects with a very large difference in mass, we can always assume that the GPE is **stored only in the smaller object**

### 3.2.2 Formulas for GPE

Formula 1

$$\Delta E_g = mg\Delta h \quad (3.3)$$

$\Delta E_g$  is the change in Potential gravitational energy (in J)

$m$  is the mass of the object (in kg)

$\Delta h$  is the change in height (in m)

$g$  is the acceleration due to gravity (in  $m/s^2$ )

Formula 2

$$E_g = mg\Delta h \quad (3.4)$$

$E_g$  is related to the GPE of the object

*Remark.* For all questions related to the **Gravational Potential Energy**, you must set your reference height in the diagram. Or, Mr McCumber will forget to add 0.5 for your test!

### 3.3 The law of the Conservation of Energy

#### 3.3.1 Boring Definitions

**Definition 3.3.1.** (*Law of the Conservation of Energy*): Energy will neither be created or destroyed, only change from one form to another

*Remark.* The law of the conservation of energy only works in a **closed isolated** system. In reality, the only true **closed and isolated** system is the Universe

#### Mechanical Energy

**Definition 3.3.2.** (*Mechanical Energy*): is the sum of the **kinetic energy** and **gravitational potential energy**.

Mathematically:

$$E_m = E_g + E_k \quad (3.5)$$

#### 3.3.2 Question solving techniques

When you solve a question about conservation of energy, always write this:

$$E_{m1} = E_{m2} \quad (3.6)$$

$$E_{k2} + E_{g2} = E_{k1} + E_{g1} + W_{ap} + W_f \quad (3.7)$$

Then, cross out terms which equal to **zero**

*Remark.* Remember to write this, or teacher will forget to add your marks!

## 3.4 String & Elastic Potential Energy

### 3.4.1 The Force of String

**Definition 3.4.1.** (*Spring Force*): Can be wrote as  $F_{spring}$ . It is the force exerted by the spring on a object.

According to the Hooke's Law, the **force exerted by a string** is proportional to the string's displacement. So we can express the relationships between them by some formulas:

Vector Version:

$$\vec{F}_x = -k\Delta\vec{x} \quad (3.8)$$

Scalar Version:

$$F_x = k\Delta x \quad (3.9)$$

$F_x$  is the force exerted by the string on whatever stretches it.

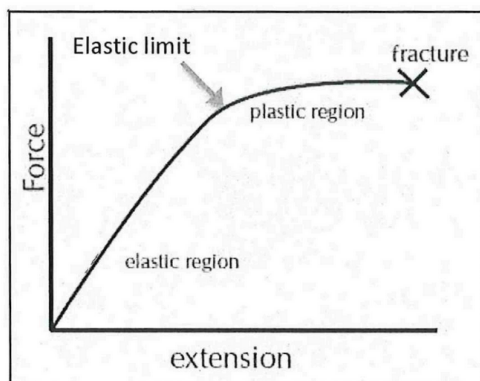
$k$  is the constant of string

$x$  is the displacement of the spring from its unstratched

An essential feature of Hooke's law is that the direction of the spring force is **opposite** to the direction of displacement from equilibrium.

*Remark.* When you use the Scalar version, you must clearly understand the direction of the force in you heart.

**Deeper explanation about Hooke's law**



**Definition 3.4.2.** (*Elastic Region*): Elastic objects obey Hooke's Law in this region. If the applied force removed, the object will naturally return back to its original shape

**Definition 3.4.3.** (*Elastic Limit*): The maximum amount of deformation an object can withstand, and still return to its original shape.

**Definition 3.4.4.** (*Plastic region*): The object no longer obeys Hooke's Law. The object's shape is now permanetly changed.

**Definition 3.4.5.** (*Fracture*): The maximum amount of shape change the object can take, prior to failing (breaking).

### 3.4.2 Elastic Potential Energy

**Definition 3.4.6.** (*elastic potential energy*): The potential energy due to the stretching or compressing of an elastic material



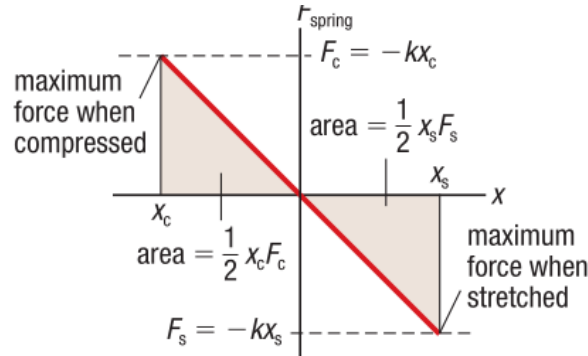


Figure 3.1: The work done by a variable force is equal to the area under the the force-displacement graph

### Formula

$$W = \frac{1}{2} * \Delta x * F_{spring} \quad (3.10)$$

$$W = \frac{1}{2} * \Delta x * (k * \Delta x) \quad (3.11)$$

$$W = \frac{1}{2} * k * (\Delta x)^2 \quad (3.12)$$

The work done by the spring force is the negative of this amount, and is also the negative of the change in Potential Energy. That means that the work done stretching or compressing the spring is transformed into elastic potential energy.

$$E_e = \frac{1}{2} k (\Delta x)^2 \quad (3.13)$$

### 3.4.3 Ignore Gravational Potential Energy

We can ignore the Gravational Potential Energy in the vertial spring question if all of these conditions are met:

- The mass remains in contact with the spring
- We measure all changes in the length relative to the equilibrium position of the mass-spring system (ie.  $x_{eq} = 0$ )

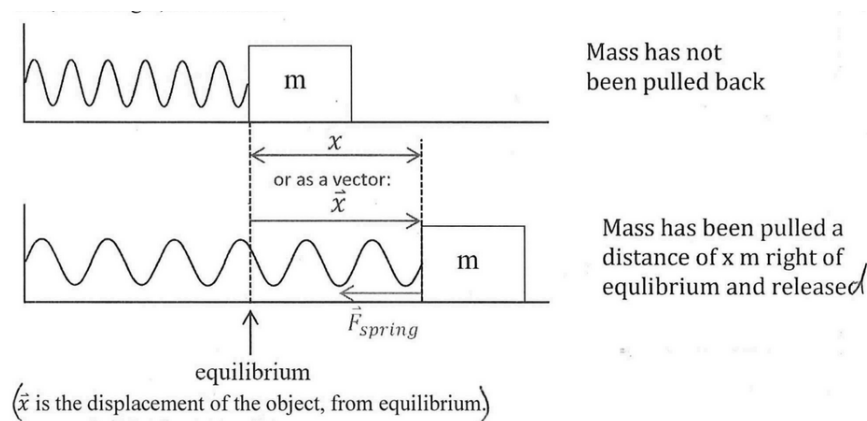
## 3.5 Simple Harmonic Motion

### 3.5.1 Definitions

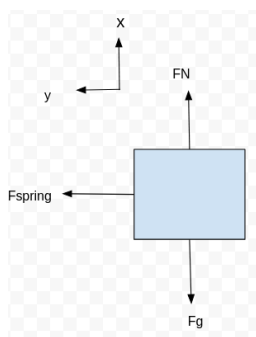
#### Simple Harmonic Motion

An object undergoes simple harmonic motion, if two conditions are met:

1. The net force acting on the object is **directly proportional** to the object's displacement away from equilibrium (The location where  $\sum F = 0$ )
2. The direction the net force acts on the object must be **opposite** the object's displacement from equilibrium.



Let see the FBD for  $m$ :



$$\sum \vec{F} = \vec{F}_{spring} \quad (3.14)$$

$$\sum \vec{F} = -k\vec{x} \quad (3.15)$$

Changing to proportionality:

$$\text{Net Force} \propto -\vec{x} \quad (3.14)$$

#### Expectations

If there was **friction** acting on the object, it would no longer undergo simple harmonic motion. We would call the motion of the object: **Damped Harmonic Motion**

Some Real life examples:

- Car shock absorbers
- A guitar string
- A pendulum or a string

- Bungee jumping

### 3.5.2 How can we solve form the acceleration of SHM

Returning to our FBD of the mass and the net force statement from it:

$$\sum \vec{F} = m\vec{a} \quad (3.15)$$

$$\vec{F}_s = m\vec{a} \quad (3.16)$$

$$-kx = m\vec{a} \quad (3.17)$$

$$a = \frac{-kx}{m} \quad (3.18)$$

$\vec{a}$  is the acceleration of the mass (in  $m/s^2$ )

$k$  is the force constant of the spring (in  $N/m$ )

$\vec{x}$  is the displacement of the mass from its equilibrium position (in m)

$m$  is the mass of the object that is attached to the spring (in kg)

*Remark.* Because the acceleration is a vector, we need to make a direction convention to use the equation.

### 3.5.3 The period of the Simple Harmonic Motion

The y-component of the uniform circular motion is similar to the acceleration of the simple Harmonic Motion

For the object going around circle:

$$a_c = \frac{4\pi^2 R}{T^2} \quad (3.19)$$

For the mass on the end of the spring:

$$\vec{a} = -\frac{k\vec{x}}{m} \quad (3.19)$$

$$|\vec{a}| = \frac{kx}{m} \quad (3.20)$$

When the object is on the top/bottom of the perfect circular motion, the acceleration is equal to the magnitude of the acceleration of the object at the equilibrium position:

$$a_c = |a| \quad (3.20)$$

$$\frac{4\pi^2 R}{T^2} = \frac{kx}{m} \quad (3.21)$$

$$T = +/ - \sqrt{\frac{m * 4\pi^2 R}{kx}} \text{ (At this time } R = x) \quad (3.22)$$

$$T = 2\pi * \sqrt{\frac{m}{k}} \quad (3.23)$$

## 3.6 Linear Momentum & Impulse

### Linear Momentum

**Linear Momentum** is the product of an object's mass and its velocity:

$$\vec{p} = m\vec{v} \quad (3.24)$$

$\vec{p}$  is the Momentum in ( $kg * \frac{m}{s}$ )

Newton called momentum "the **true Quantity of motion**". Why? Momentum is a combination of an object's **inertia**(its mass basically) and what it is doing (its **velocity**). He felt that it provided a more complete picture of what was required to cause a specific change in what an object was doing.

### Impulse

Impulse is the **product of that force** acting on an object and the **duration** of time that the force acted on the object.

$$\vec{J} = \vec{F} * \Delta t \quad (3.25)$$

$\vec{J}$  = the impulse in (N\*s)

The formula has a similar limitation to the formula for the work done on an object. Both formulas assume that the force acting on the object.

Thus, if the force acting on the object is not constant, we can find the impulse that the force provides by finding the area between the line/curve on a **Force vs Gravity graph**

Let's see some formula:

$$\begin{aligned} \sum \vec{J} &= \sum \vec{F} * \Delta t \\ \sum \vec{J} &= (m * \vec{a}) * \Delta t \\ \sum \vec{J} &= (m * \frac{\vec{v}_2 - \vec{v}_1}{\Delta t}) * \Delta t \\ \sum \vec{J} &= m * \vec{v}_2 - m * \vec{v}_1 \\ \sum \vec{J} &= \vec{p}_2 - \vec{p}_1 \\ \sum \vec{J} &= \Delta \vec{p} \end{aligned} \quad (3.26)$$

### 3.7 Conservation of Momentum

**Definition 3.7.1.** Two or more objects interact and **exert forces from each other**. The forces in the interaction are a Newton's Third Law pair of forces (ie  $\vec{F}_{A/B} = -\vec{F}_{B/A}$ )

#### 3.7.1 Equation

Consider a person standing on any icy surface throws a heavy object horizontally:

FBD for the person (Left) and the object (Right)

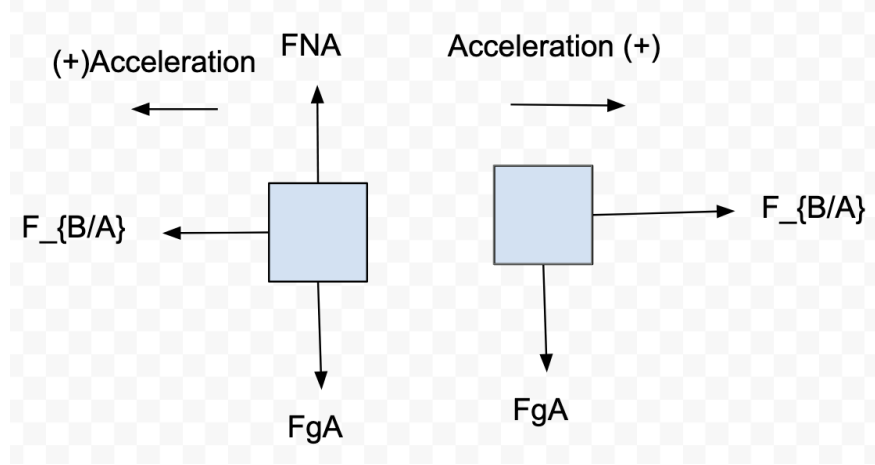


Figure 3.2: We will assume that the interaction forces are essentially the net force acting on the object

Equation for the object A:

$$\begin{aligned}\sum \vec{F}_A &= m_A * \vec{a}_A \\ \vec{F}_{B/A} &= m_A \vec{a}_A \\ \vec{F}_{B/A} &= m_A \frac{\vec{v}_{fA} - \vec{v}_{iA}}{\Delta t_A}\end{aligned}\tag{3.27}$$

Equation for the object B:

$$\begin{aligned}\sum \vec{F}_B &= m_B * \vec{a}_B \\ \vec{F}_{A/B} &= m_B \vec{a}_B \\ \vec{F}_{A/B} &= m_B \frac{\vec{v}_{fB} - \vec{v}_{iB}}{\Delta t_B}\end{aligned}\tag{3.28}$$

**Lemma 3.7.2.** From Newton's third law, we know  $\vec{F}_{A/B} + \vec{F}_{B/A} = 0$

We add 3.27 and 3.28 together:

$$m_A \frac{\vec{v}_{fA} - \vec{v}_{iA}}{\Delta t_A} + m_B \frac{\vec{v}_{fB} - \vec{v}_{iB}}{\Delta t_B} = 0$$

We know the time for both object should be the same.

$$\begin{aligned}m_A * \vec{v}_{fA} + m_B * \vec{v}_{fB} &= m_A * \vec{v}_{iA} + m_B * \vec{v}_{iB} \\ \vec{P}_{A2} + \vec{P}_{B2} &= \vec{P}_{A1} + \vec{P}_{B1}\end{aligned}\tag{3.29}$$

3.29 is the law of **Conservation of Momentum**

Always write this line at the beginning of your analysis

**Definition 3.7.3.** (*The Law of Conservation of Momentum*): The total momentum of a system of objects after an interaction is **equal** to the total momentum of the system before the interaction.

According to the 3.7.3, we can understand the total momentum of the system is **constant through out** the interaction.

The law assume that any other force that could **accelerate** any objects in the system during the interaction is **negligible**

## 3.8 Types of Collisions

### 3.8.1 Definitions

Collisions are typically classified based on the amount of **kinetic energy** the system has after the collision, in comparison to the amount of kinetic energy the system had before the collision. In other words, **how does  $E'_k$  with  $E_k$ ?**

### 3.8.2 Elastic Collisions

In an elastic collision, the kinetic energy of the system after the collision is **equal** to the kinetic energy of the system before the collision. In mathematics, the equation can be represented by:

$$E_k' = E_k$$

*Remark.* This does not mean the kinetic energy of the system after the collision is **equal** to the kinetic energy of the system before the collision (Unlike momentum)

#### Steps of the collision

*Remark.* This is on a horizontal frictionless surface, so we can ignore Gravitational Potential Energy

**Before the collision:** The mechanical energy is entirely in the form of kinetic energy

**First half of collision:** The interaction forces cause the object to start deform. As the object deforms, they transfer  $E_k$  to  $E_s$ .

**At the approximate midpoint of the collision:** The deformation of the object is at a maximum.  $E_s$  is the maximum and  $E_k$  is the minimum.

**During the second half of the collision:** The restoring forces are now doing *positive work* on the system, transferring elastic potential energy **back into**  $E_k$

**After the collision:** The system's mechanical energy is now entirely  $E_k$ , at this time,  $E_s = 0$ . All  $E_s$  is transferred to  $E_k$ .

#### Head-on Collision

**Before the Collision:** System's mechanical energy is entirely  $E_k$

**During the first half of the collision:** The spring gets compressed.  $E_k$  is transformed into  $E_s$ .

**At the mid-point of the collision:**

- Spring is at the most compressed point.
- Distance between cars is minimized
- $\vec{v}_A = \vec{v}_B$
- $E_k$  is minimized
- $E_s$  is maximized

**During the second half of the collision:**

- $\vec{v}_A < \vec{v}_B$
- Distance between the carts is increasing

- $E_s$  is being transferred back into  $E_k$

**After the collision:** The system is entirely  $E_k$  now

*Remark.* Elastic collisions **cannot occur** between visible objects in real life. At least some of the energy will be lost as thermal or sound.

### 3.8.3 Inelastic Collision

So for this collision,  $E_k'$  is less than  $E_k$

It is impossible for a system to have more kinetic energy after the collision, than it had before the collision, unless:

1. One of the object had **stored energy** before the collision, which was transferred into kinetic energy during the collision.
2. An **external** force (such as force of gravity) is doing positive work on the system, during the collision.

#### Completely inelastic collision

In this collision, the maximum amount of kinetic energy that could be "lost" is lost as a result of the collision.

After the collision, the objects involved in the collision will be **stack/attached together**

**Apple and Arrow** is an example of this question.

The following condition must be met for a Perfectly Inelastic Collision:

- $\vec{v}_A' = \vec{v}_B' = \vec{v}$



## 3.9 HEAD-ON Collisions

### 3.9.1 Equations

Under this section, I will derive Equations that is useful to solve for final velocity for each object when you have initial velocity for a HEAD-ON Collision question

The equation for  $\vec{v}_A'$

$$\vec{v}_A' = \frac{m_A - m_B}{m_A + m_B} * \vec{v}_A \quad (3.30)$$

The equation for  $\vec{v}_B'$

$$\vec{v}_B' = \frac{2m_A}{m_A + m_B} * \vec{v}_A \quad (3.31)$$

For questions which  $\vec{v}_B$  is not zero, we need change Frame of Reference to  $\vec{v}_B$  in order to solve the question. And change the FOR back later.