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# Accelerated motion

*t* = *t*2

*x* = *x*2

*t* = *t*3

*x* = *x*3

*t* = *t*1

*x* = *x*1

*t* = 0

*x* = *x*0

*v*0

  

# Resistor

# Secant method

Start

*f*(*x*), *x*1, *x*2, *ε*

*n* = 1

2

1

*c* < ε

*c* = | *f*(*xn*+2)|

2

1

*n* = *n* + 1

N

*x*root *= xn*+2

*x*root

End

Y



# Regula falsi method

Start

*f*(*x*), *x*1, *x*2, *ε*

*n* = 1

2

1

*c* < ε

*c* = | *f*(*xn*+2)|

2

1

*n* = *n* + 1

N

*x*root *= xn*+2

*x*root

End

Y



# DC circuit R and ε

*R*1

*R*2

*R*3

*R*4

*R*5

*R*6

*R*7

*R*8

*ε*1

*ε*3

*ε*2

*I*1

*I*2

*I*1 + *I*2

*I*1

*I*2

*I*3

*I*3

*I*1

*I*1

*I*1 – *I*3

*I*1 – *I*3

*I*2 + *I*3

*I*2

*I*2

*I*3

*I*3

*I*3

*I*3

*I*3

*I*3

*I*2 + *I*3

*I*1 + *I*2

*a*

*b*

*c*

*d*

# Kinematics optimization(?)

*A*1

*A*2

*A*3

0

*t*up

*t*down

*t*stop

*v*max

*v*

*t*

   

   

  

 









# Notes and version

* 130% (Jekyll + MathJax), save as 0000x first then save as back to 0000, remove 0000x then, x = i
* 20210209