B- Ashak

A therdance

,

0.'---

20

Endlam 60

while all de la fe hile als feed on his above all

Ist law Inestal systems exist. Af A Tensors

h an inestial coord system of that
is many with some constant vel. i continue
to do so while undistricted.

2nd law the Rate of change of a nomentum of a
system equal the force ackny on it

of (mi) = = or = ma for const.

3nd law Action & reaching are equal & opposite.

Fi = Fi di = is still affirmed or of (Fi + Fi) = 0

Projectile motion. Acceleration
$$\vec{a}(t) = d\vec{v}$$
.

Integrale: $\vec{v}(t) = \vec{v}(t_0) + \int \vec{a}(t) dt$

For uniform acceleration to

 $\vec{v}(t) = \vec{v}(t_0) + \vec{a}t$
 $\vec{d}\vec{v} = \vec{v}(t)$
 $\vec{r}(t) = \vec{r}(t) = \vec{r}(t_0) + \vec{a}t$
 $\vec{r}(t) = \vec{r}(t_0) + \vec{r}(t_0)$

In a uniform growitational field: $1^{\frac{1}{2}}$ An object is thrown upwould at two with

Some unit. wel. V_0 $x = x_0 + v_x t$ To obtain the trajectory, $y = y_0 + v_x t$ eliminate time $t' = x_0 + \int_0^t (v_0 x_0 - gt') dt'$ for sumplicity, $f(x_0) = v_0 t - \int_0^t g(t') dt'$ consider $f(x_0) = v_0 t - \int_0^t g(t') dt'$ $f(x_0) = v_0 t - \int_0^t g(t') dt'$

This slide left blank for whiteboard

$$t = \frac{x}{v_{ex}}$$

$$z = \frac{v_{ex}}{v_{a}} \times - \frac{1}{2} \frac{9x^{2}}{v_{ex}^{2}}$$

$$z = \frac{v_{ex}}{v_{a}} \times - \frac{1}{2} \frac{9x^{2}}{v_{ex}^{2}}$$

$$z = \frac{x}{v_{a}} \times - \frac{1}{2} \frac{9x^{2}}{v_{ex}^{2}}$$

$$z = \frac{x}{v_{ex}} \times - \frac{1}{2} \frac{9x^{2}}{v_{ex}^{2}}$$

$$z =$$

This slide left blank for whitehoard

Principle of least action or Hamilton's principle.

How do we find the shortest path betw 2 points.

ie. how do you find a goodesic? $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}) & \text{dt} \\ \text{Goods} \end{cases}$ $I = \begin{cases} L(t, q, \dot{q}$

$$I = \int_{t_1}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$dI = \int_{t_1}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_1}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_1}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_1}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$

$$= \int_{t_2}^{t_2} \left(g_1 g_1 t \right) dt \left| g = Q(t) + en(t) \right|$$





