THE 18.821 MATHEMATICS PROJECT LAB REPORT [PROOFS]

JONATHAN ALLEN

1. Theorems

1.1. Notation.

t**:** Time
$l(t)$**:** Path length
$s(t)$**:** Speed
$a_t(t)$**:** Tangential acceleration
$a_c(t)$**:** Centripetal acceleration
$\vec{x}(t)$**:** Position
$\vec{v}(t)$**:** Velocity
$\vec{a}(t)$**:** Acceleration

2. Coordinate Systems

$$\dot{a} = \frac{da}{dt} \tag{1}$$

2.1. Rectangular Coordinates.

$$R = \left| \frac{(\dot{x}^2 + \dot{y}^2)^{3/2}}{\dot{x}\ddot{y} - \dot{y}\ddot{x}} \right| \tag{2}$$

(for $a_c =$)
$$= \left| \frac{s^2}{a_t} \right|$$

2.2. Scalar Calculus in Polar Coordinates.

$$s = \frac{dl}{dt} \tag{3}$$

$$a_t = \frac{ds}{dt} \tag{4}$$

(5)

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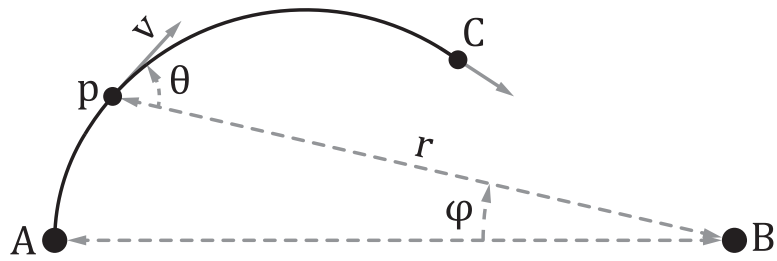

Proof.

FIGURE 1. My first .eps figure.

2.3. **Vector Calculus in Polar Coordinates.**

$$\boldsymbol{x} = r\hat{\boldsymbol{r}} \tag{6}$$

$$\vec{\boldsymbol{v}} = \dot{r}\hat{\boldsymbol{r}} + r\dot{\phi}\hat{\boldsymbol{\phi}} \tag{7}$$

$$\vec{\boldsymbol{a}} = \left(\ddot{r} - r\dot{\phi}^2\right)\hat{\boldsymbol{r}} + \frac{1}{r}\frac{d}{dt}\left(r^2\dot{\phi}\right)\hat{\boldsymbol{\phi}} \tag{8}$$

2.4. **Relations.**

$$l = \int_{t=0}^{T} \|\vec{\boldsymbol{v}}\| \, dt \tag{9}$$

$$s = \|\vec{\boldsymbol{v}}\| \tag{10}$$

$$a_t = \|\vec{\boldsymbol{a}}\| \cdot \hat{\boldsymbol{v}} = \|\vec{\boldsymbol{a}}\| \cdot \frac{\vec{\boldsymbol{v}}}{\|\vec{\boldsymbol{v}}\|} \tag{11}$$

$$a_c = \|\vec{\boldsymbol{a}}\| \times \hat{\boldsymbol{v}} = \|\vec{\boldsymbol{a}}\| \times \frac{\vec{\boldsymbol{v}}}{\|\vec{\boldsymbol{v}}\|} \tag{12}$$

3. Lemmas and Definitions

Lemma 3.1. *If $a_t = 0$ and $\|a_c\| \leq a_{c,max}$, then the minimum radius of curvature of a point trajectory is given by*

$$R_{min} = \frac{v^2}{a_{c,max}} \tag{13}$$

If we look at a position, p, on a trajectory. We can align a rectangular coordinate system with this point, such that $\hat{y} = \hat{v}$.

$$a_c = \ddot{r} - r\dot{\phi}^2 \tag{14}$$

$$a_t = \frac{1}{r}\frac{d}{dt}\left(r^2\dot{\phi}\right) \tag{15}$$

$$0 = \frac{1}{r}\frac{d}{dt}\left(r^2\dot{\phi}\right) \tag{16}$$

$$r^2\dot{\phi} = constant \tag{17}$$

□

4. Theorems

Theorem 4.1. *If $a_t = 0$ and $\|a_c\| \leq a_{c,max}$, it is always optimal to minimize the turning radius.*

Proof.

$$\vec{\boldsymbol{v}} = \dot{r}\hat{\boldsymbol{r}} + r\dot{\phi}\hat{\boldsymbol{\phi}} \tag{18}$$

$$s = \sqrt{\dot{r}^2 + r^2\dot{\phi}^2} \tag{19}$$

$$\dot{r} = s^2 - r^2\dot{\phi}^2 \tag{20}$$

□

References

[1] http://en.wikipedia.org/wiki/Polar_coordinate_system