

Non-Inertia Frames

Dr H. Wang

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1 Rotating Frames

From an inertial frame, the speed is

$$\dot{\mathbf{r}} = \boldsymbol{\omega} \times \mathbf{r},$$

and the different measure of velocities are related by

$$\left(\frac{d\mathbf{r}}{dt} \right)_S = \left(\frac{d\mathbf{r}}{dt} \right)_{S'} + \boldsymbol{\omega} \times \mathbf{r}.$$

The acceleration:

$$\left(\frac{d^2\mathbf{r}}{dt^2} \right)_S = \left(\frac{d^2\mathbf{r}}{dt^2} \right)_{S'} + 2\boldsymbol{\omega} \times \left(\frac{d\mathbf{r}}{dt} \right)_{S'} + \dot{\boldsymbol{\omega}} \times \mathbf{r} + \boldsymbol{\omega} \times (\boldsymbol{\omega} \times \mathbf{r}). \quad (1)$$

2 Newton's Equation of Motion in a Rotating Frame

$$m \left(\frac{d^2\mathbf{r}}{dt^2} \right)_{S'} = \mathbf{F} - 2m\boldsymbol{\omega} \times \left(\frac{d\mathbf{r}}{dt} \right)_{S'} - m\dot{\boldsymbol{\omega}} \times \mathbf{r} - m\boldsymbol{\omega} \times (\boldsymbol{\omega} \times \mathbf{r})., \quad (2)$$

3 Euler Force

$$\mathbf{F}_{\text{euler}} = -m\dot{\boldsymbol{\omega}} \times \mathbf{r}. \quad (3)$$

4 Centrifugal Force

$$\begin{aligned}\mathbf{F}_{\text{cent}} &= -m\boldsymbol{\omega} \times (\boldsymbol{\omega} \times \mathbf{r}) \\ &= -m(\boldsymbol{\omega} \cdot \mathbf{r})\boldsymbol{\omega} + m(\boldsymbol{\omega} \cdot \boldsymbol{\omega})\mathbf{r}\end{aligned}\tag{4}$$

The first term of (4) is related to the projection of \mathbf{r} on to $\boldsymbol{\omega}$, denoted as \mathbf{r}_{\parallel} by

$$-m(\boldsymbol{\omega} \cdot \mathbf{r})\boldsymbol{\omega} = -m\omega^2\mathbf{r}_{\parallel}$$

Since the second term is effectively $m\omega^2\mathbf{r}$, we can then deduce

$$\mathbf{F}_{\text{cent}} = m\omega^2\mathbf{r}_{\perp},$$

where \mathbf{r}_{\perp} is the projection of \mathbf{r} on to the plane perpendicular to $\boldsymbol{\omega}$.

5 Coriolis Force

$$\mathbf{F}_{\text{cor}} = -2m\boldsymbol{\omega} \times \mathbf{v}\tag{5}$$

where $\mathbf{v} = (\mathrm{d}\mathbf{r}/\mathrm{d}t)_{S'}$ is the velocity of the particle measured in the rotating frame S' .