

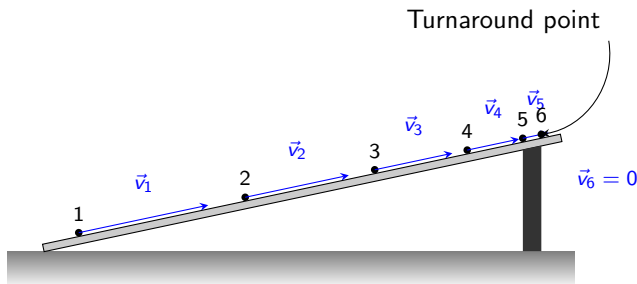
PHYS2350: Acceleration in 1D

Dr. Wolf

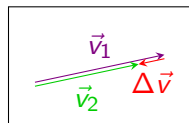
Fall 2024

Summary: Motion with decreasing speed

Making a velocity diagram:

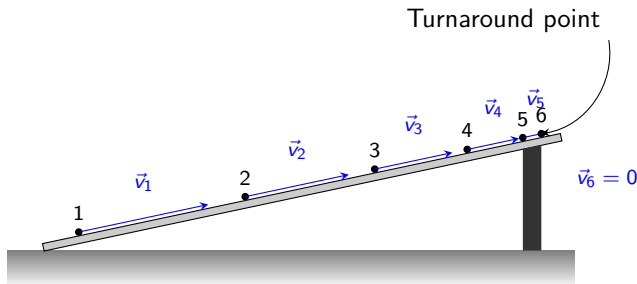


- All velocity vectors point *up the ramp*
- All change in velocity vectors $\Delta \vec{v} = \vec{v}_f - \vec{v}_i$ point *down the ramp*

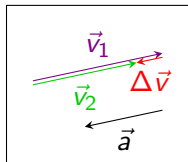


Summary: Motion with decreasing speed

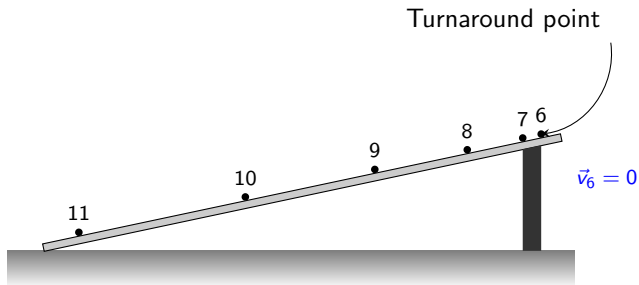
Making a velocity diagram:



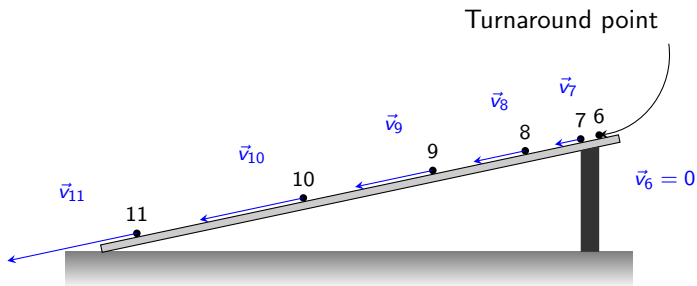
- Acceleration vector is *constant* in magnitude and direction
- Acceleration is $\vec{a} = \frac{\Delta \vec{v}}{\Delta t}$ and points *down the ramp*



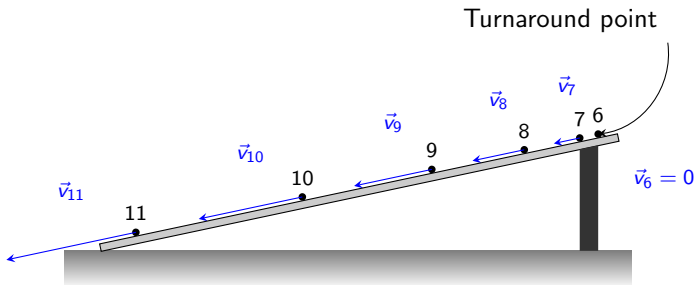
Motion with increasing speed



Motion with increasing speed



Motion with increasing speed



Summary:

- $\Delta \vec{v}$ is always in the same direction as \vec{v}
- \vec{a} is always in the same direction as \vec{v}
- $\Delta \vec{v}$ and \vec{a} are always pointing *down the ramp*.

Motion that includes a change in direction

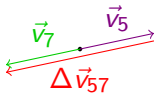
Consider the velocity at instants 5 and 7:



Find the *change in velocity* vector, Δv for this scenario

Motion that includes a change in direction

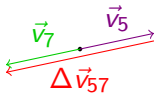
Consider the velocity at instants 5 and 7:



Find the *change in velocity* vector, Δv for this scenario

Motion that includes a change in direction

Consider the velocity at instants 5 and 7:



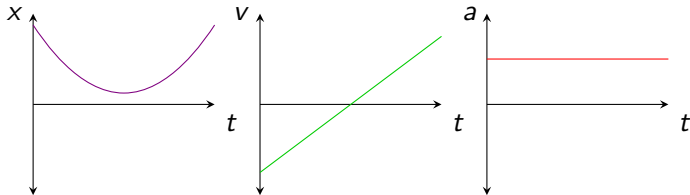
Find the *change in velocity* vector, $\Delta \vec{v}$ for this scenario

Direction of $\Delta \vec{v}$ and \vec{a}

- $\Delta \vec{v}$ and \vec{a} are always pointing *in the same direction*.
- $\Delta \vec{v}$ and \vec{a} are always pointing *down the ramp*.

Make a graph

For the motion of the ball on the ramp, make graphs of x vs. t , v vs. t , and a vs. t . Choose the $+x$ direction to be *down the ramp*



Kinematic equations in 1D

Also called the “Constant acceleration equations”.

$$x(t) = x_i + v_i t + \frac{1}{2} a t^2 \quad (1)$$

$$v(t) = v_i + a t \quad (2)$$

$$v_f^2 - v_i^2 = 2a(x_f - x_i) \quad (3)$$

Equation (3) is obtained by solving (2) for t and plugging into (1), then simplifying. It assumes $x(t) = x_f$ and $v(t) = v_f$.