Physics Notes

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1 Measurement

1.1 Instrument Uncertainty

All instruments have uncertainty:

1. Analogue Instruments: Half the smallest measurement unit
2. Digital Instruments: The smallest significant figure
3. Human reaction time: ± 0.10s

1.2 Significant Figures

1. Adding or subtracting: Follow term with least *decimal place*
2. Multiplying or Dividing: Follow term with least *significant figure*

1.3 Propagation of error

For any $f(a, \cdots)$ the general formula for Δf is:

$$\Delta f = \sqrt{\left(\frac{\partial f}{\partial a}\Delta a\right)^2 + \cdots}$$

Some specific examples:

1. $f = a \pm b$

$$\Delta f = \sqrt{(\Delta a)^2 + (\Delta b)^2}$$

2. $f = ab$ or $f = \frac{a}{b}$

$$\frac{\Delta f}{f} = \sqrt{\left(\frac{\Delta a}{a}\right)^2 + \left(\frac{\Delta b}{b}\right)^2}$$

2 Mechanics

2.1 Statics

When all objects are motionless (or have constant velocity),

$$\sum \boldsymbol{F}_{net} = 0$$
$$\sum \boldsymbol{\tau}_{net} = 0$$

Four basic forces to consider:

Tension Pulling force felt by a rope, string, etc. Every piece of rope feels a pulling force in both directions.

Friction Parallel to surface of contact, can be static or kinetic.

Normal Perpendicular to surface of contact, prevents object from falling through surface.

Gravity Force acting between two objects with mass. Always acts downwards for objects on surface of earth.

2.2 Kinematics

$$\boldsymbol{v} = \lim_{\Delta t \to 0} \frac{\Delta \boldsymbol{x}}{\Delta t} = \frac{d\boldsymbol{x}}{dt} = \dot{\boldsymbol{x}}$$
$$\boldsymbol{a} = \frac{d\boldsymbol{v}}{dt} = \frac{d^2\boldsymbol{x}}{dt^2} = \dot{\boldsymbol{x}} = \ddot{\boldsymbol{x}}$$

2.2.1 Polar Coordinates

Differentiation of unit vectors:

$$\dot{\hat{\boldsymbol{r}}} = \dot{\theta}\hat{\boldsymbol{\theta}}$$
$$\dot{\hat{\boldsymbol{\theta}}} = -\dot{\theta}\hat{\boldsymbol{r}}$$

Velocity and acceleration in polar form:

$$\boldsymbol{r} = r\hat{\boldsymbol{r}}$$
$$\boldsymbol{v} = \dot{\boldsymbol{r}} = \dot{r}\hat{\boldsymbol{r}} + r\dot{\theta}\hat{\boldsymbol{\theta}}$$
$$\boldsymbol{a} = \dot{\boldsymbol{v}} = (\ddot{r} - \dot{\theta}^2 r)\hat{\boldsymbol{r}} + (r\ddot{\theta} + 2\dot{r}\dot{\theta})\hat{\boldsymbol{\theta}}$$

2.3 Dynamics

$$\boldsymbol{F} = m\ddot{\boldsymbol{x}}$$
$$\boldsymbol{F}_{action} = -\boldsymbol{F}_{reaction}$$

Free body diagram techniques:

1. $\Sigma \boldsymbol{F}_{net} = 0$ for massless pulleys
2. Conservation of string

Solving differential equations in 1-dimension:

1. $F = f(t)$

$$m\int_{v_0}^{v(t)} dv' = \int_{t_0}^{t} f(t')dt'$$
$$m\int_{x_0}^{x(t)} dx' = \int_{t_0}^{t} v(t')dt'$$

2. $F = f(x)$

$$a = \frac{dv}{dt} = \frac{dv}{dt}\frac{dx}{dx} = v\frac{dv}{dx}$$
$$m\int_{v_0}^{v(x)} v'dv' = \int_{x_0}^{x} f(x')dx'$$

3. $F = f(v)$

$$m\int_{v_0}^{v(t)} \frac{dv'}{f(v')} = \int_{t_0}^{t} dt'$$

2.3.1 Friction

Kinetic and static friction:

$$\boldsymbol{f_k} = \mu_k \boldsymbol{N}$$
$$\boldsymbol{f_s} \leq \mu_s \boldsymbol{N}$$

Static friction does no work.

2.3.2 Constraining Forces

For any rigid body, there are 6 degrees of freedom (DF). There can be constraining forces (C) acting on the body.

- Statics: $C + DF = 6$
- Dynamics $C + DF \geq 6$

There are 3 assumptions made for a body moving without any constraint:

1. $\boldsymbol{f}_{ij} \parallel \boldsymbol{r}_{ij}$
2. $\boldsymbol{r}_{ij}$ is constant for any 2 points in a rigid body
3. $\boldsymbol{f}_{12} + \boldsymbol{f}_{21} = 0$

2.3.3 Fictitious Forces

For any vector $\boldsymbol{A}$ in a moving frame, we calculate its time derivative in a frame rotating at ω respect to the stationary frame:

$$\frac{d\boldsymbol{A}}{dt}_{\text{stat}} = \frac{d\boldsymbol{A}}{dt}_{\text{mov}} + \boldsymbol{\omega} \times \boldsymbol{A}$$

Let $\boldsymbol{r}$ be the position vector of the object in an accelerated frame and $\boldsymbol{R}$ be the vector to the origin of the accelerated frame, then the possible forces that acts on $\boldsymbol{r}$ in the moving frame are:

$$\frac{d^2\boldsymbol{r}}{dt^2} = \frac{\boldsymbol{F}}{m} - \frac{d^2\boldsymbol{R}}{dt^2} - \boldsymbol{\omega} \times (\boldsymbol{\omega} \times \boldsymbol{r}) - 2\boldsymbol{\omega} \times \boldsymbol{v} - \frac{d\boldsymbol{\omega}}{dt}\boldsymbol{r}$$

1. Translational force: $-m\frac{d^2\boldsymbol{R}}{dt^2}$
2. Centrifugal force: $-m\boldsymbol{\omega} \times (\boldsymbol{\omega} \times \boldsymbol{r})$
3. Coriolis force: $-2m\boldsymbol{\omega} \times \boldsymbol{v}$
4. Azimuthal force: $-m\frac{d\boldsymbol{\omega}}{dt}\boldsymbol{r}$

2.4 Conservation Laws

Energy $W_{NC} = 0$

Momentum $\Sigma \boldsymbol{F}_{net} = 0$

Angular Momentum $\Sigma \boldsymbol{\tau}_{net} = 0$

2.5 Energy

For a force in one dimension:

$$m\dot{\boldsymbol{r}}\frac{d\dot{\boldsymbol{r}}}{d\boldsymbol{r}} = \boldsymbol{F}(\boldsymbol{r})$$
$$\frac{1}{2}m|\dot{\boldsymbol{r}}|^2 = E + \int_{\boldsymbol{r_0}}^{\boldsymbol{r}} \boldsymbol{F}(\boldsymbol{r}')\cdot d\boldsymbol{r}'$$

We can then define *potential energy*:

$$U(\boldsymbol{r}) = -\int_{\boldsymbol{r_0}}^{\boldsymbol{r}} F(\boldsymbol{r}')\cdot d\boldsymbol{r}'$$

Work-Energy theorem:

$$W_{AB} = \int_{\boldsymbol{r_1}}^{\boldsymbol{r_2}} F(\boldsymbol{r}')\cdot d\boldsymbol{r}'$$
$$W_{\text{total}} = \Delta KE$$

Conservative forces are forces that only depend on *position*. For conservative forces:

$$\oint \boldsymbol{F}\cdot d\boldsymbol{r} = 0$$
$$\boldsymbol{\nabla}\times\boldsymbol{F} = 0$$
$$\boldsymbol{F} = -\boldsymbol{\nabla}U$$
$$W_C = -\Delta U$$

For non-conservative forces:

$$W_{NC} = \Delta(K+U) = \Delta E$$

Where E is defined as the mechanical energy of the system.

2.5.1 Energy Analysis

The Lagrangian method is based on the *principle of stationary action.*

$$\mathcal{L}(\dot{x},x,t) = T - V$$
$$\frac{d}{dt}\left(\frac{\partial\mathcal{L}}{\partial\dot{x}}\right) - \frac{\partial\mathcal{L}}{\partial x} = 0$$

The Hamiltonian $\mathcal{H}$ can be used for the conservation of energy:

$$\mathcal{H}(\dot{x},x,t) = T + V$$
$$\dot{\mathcal{H}} = 0$$

Where T is the kinetic energy, and V is the potential energy of the system.

2.5.2 Power

Power is the rate of work done per unit time:

$$P = \frac{dW}{dt}$$

Mechanical power:

$$P = \frac{d}{dt}\oint \boldsymbol{F}\cdot d\boldsymbol{r} = \frac{d}{dt}\oint \boldsymbol{F}\cdot\frac{d\boldsymbol{r}}{dt}dt$$
$$= \boldsymbol{F}\cdot\boldsymbol{v}$$

2.6 Momentum

Momentum is defined as:

$$\boldsymbol{p} = m\boldsymbol{v}$$

When there is no net force on the system,

$$\sum \boldsymbol{F}_{net} = 0 \Rightarrow \frac{d\boldsymbol{p}}{dt} = 0$$
$$\Rightarrow \boldsymbol{p} \text{ is conserved}$$

Impulse is defined as:

$$\mathcal{I} = \int_{t_1}^{t_2}\boldsymbol{F}(t)dt = \int_{t_1}^{t_2}\frac{d\boldsymbol{p}}{dt}dt$$
$$\mathcal{I} = \boldsymbol{p}(t_2) - \boldsymbol{p}(t_1) = \Delta\boldsymbol{p}$$

For perfectly elastic collisions of two objects in 1-D, relative velocity is constant.

$$\boldsymbol{v}_1 - \boldsymbol{v}_2 = -(\boldsymbol{v}_1' - \boldsymbol{v}_2')$$

For other collisions in 1-D, we have the coefficient of restitution e:

$$e = -\frac{\boldsymbol{v}_2' - \boldsymbol{v}_1'}{\boldsymbol{v}_2 - \boldsymbol{v}_1} \qquad 0 \le e \le 1$$

2.7 Central Forces

For any particle subjected to a central force,

$$F(r) = m\ddot{r} - mr\dot{\theta}^2$$
$$L = mr^2\dot{\theta}$$

Because angular momentum L is constant, we can look at central forces systems in 1-dimension.

$$V_{\text{eff}}(r) = \frac{L^2}{2mr^2} + V(r)$$
$$E = V_{\text{eff}} + \frac{1}{2}m\dot{r}^2$$

2.7.1 Gravity

For any two point masses of m_1 and m_2 in empty space, the gravitational force between them is:

$$\boldsymbol{F} = \frac{Gm_1m_2}{|\boldsymbol{r}|^2}\hat{\boldsymbol{r}}$$

Where $\boldsymbol{r}$ is the position vector of one mass respect to the other, and G is the gravitational constant.

$$F = mg$$

For a mass m at the Earth's surface, where $g = 9.81m/s^2$ pointing downwards.

2.8 Uniform Circular Motion

For a point mass moving in uniform circular motion, we define:

$$\omega = \frac{v}{r}$$

The centripetal acceleration a and the force required to keep the object in its circular path:

$$a = \frac{v^2}{r} = \omega^2 r$$
$$F = \frac{mv^2}{r} = m\omega^2 r$$

2.9 Rotational Dynamics (Constant $\hat{\boldsymbol{L}}$)

2.9.1 Angular Momentum

The angular momentum of a point mass is defined as:

$$\boldsymbol{L} = \boldsymbol{r}\times\boldsymbol{p}$$

For a flat object lying on a 2-D plane rotating with angular speed ω:

$$\boldsymbol{L} = \int \boldsymbol{r}\times\boldsymbol{p} = \int r^2\omega\hat{\boldsymbol{z}}dm$$

If we define the *moment of intertia* about the z-axis to be $I_z = \int(x^2+y^2)dm$, we have:

$$L_z = I_z\omega$$
$$T = \int\frac{1}{2}m\boldsymbol{v}^2 = \int\frac{r^2\omega^2}{2}dm$$
$$= \frac{1}{2}I_z\omega^2$$

For the z-component of $\boldsymbol{L}$ and kinetic energy T.

2.9.2 General Motion

For an object with a moving center of mass, and rotating at ω about it,

$$\boldsymbol{L} = \boldsymbol{r}_{\text{CM}} \times \boldsymbol{p}_{\text{CM}} + I_{\text{CM}}\omega\hat{\boldsymbol{z}}$$
$$T = \frac{1}{2}mv_{\text{CM}}^2 + \frac{1}{2}I_{\text{CM}}\omega^2$$

2.9.3 Torque

Torque is defined as:

$$\boldsymbol{\tau} = \boldsymbol{r} \times \boldsymbol{F}$$

Using an origin satisfying any of the following conditions to calculate $\boldsymbol{L}$,

1. The origin is the center of mass
2. The origin is not accelerating
3. $(\boldsymbol{R} - \boldsymbol{r_0})$ is parallel to $\boldsymbol{r_0}$, the position of the origin in a fixed coordinate system

$$\frac{d\boldsymbol{L}}{dt} = \sum \boldsymbol{\tau}_{\text{ext}}$$

When there is no external torque, we have the conservation of angular momentum.

$$\boldsymbol{\tau}_{\text{ext}} = I\alpha$$

Where $\alpha = \frac{d\omega}{dt}$ is the angular acceleration.

2.9.4 Angular Impulse

Angular impulse is defined as:

$$\mathcal{I}_\theta = \int_{t_1}^{t_2} \boldsymbol{\tau}(t)dt = \Delta\boldsymbol{L}$$

If we have a force $\boldsymbol{F}(t)$ applied at a constant distance R from the origin,

$$\boldsymbol{\tau}(t) = \boldsymbol{R} \times \boldsymbol{F}(t)$$
$$\mathcal{I}_\theta = \boldsymbol{R} \times \mathcal{I}$$
$$\Delta\boldsymbol{L} = \boldsymbol{R} \times (\Delta\boldsymbol{p})$$

2.9.5 Parallel-axis Theorem

Let an object of mass M rotate about its center of mass with the same frequency ω as the center of mass rotates about the origin (with radius R):

$$L_z = (MR^2 + I_{\text{CM}})\omega$$

Thus if the moment of inertia of an object is I_0 about a particular axis, its moment of inertia about a parallel axis separated by R is:

$$I = MR^2 + I_0$$

2.9.6 Perpendicular-axis Theorem

For flat 2-D objects in the x-y plane, and orthogonal axes x, y and z:

$$I_z = I_x + I_y$$

2.9.7 Moments of Inertia

Center of mass for an object of mass M:

$$\boldsymbol{R}_{\text{CM}} = \frac{\int \boldsymbol{r}dm}{M}$$

Common moments of inertia (taken about center of mass unless stated):

1. Point mass at r from axis: mr^2
2. Rod of length L about center: $\frac{1}{13}mL^2$
3. Rod of length L about one end: $\frac{1}{3}mL^2$
4. Solid disk of radius r perpendicular to axis: $\frac{1}{2}mr^2$
5. Hollow sphere with radius r: $\frac{2}{3}mr^2$
6. Solid sphere with radius r: $\frac{2}{5}mr^2$

2.10 General Rotational Motion

For any body moving in space, its motion can be written as a sum of its translational motion and a rotation about an axis at a particular time.

2.10.1 Angular Velocity

The angular velocity vector $\boldsymbol{\omega}$ points along the axis of rotation, with a magnitude equal to its angular speed. Its direction is determined by convention of the right hand rule. For an object rotating at $\boldsymbol{\omega}$, the velocity of a point at $\boldsymbol{r}$ is:

$$\boldsymbol{v} = \boldsymbol{\omega} \times \boldsymbol{r}$$

Angular velocities add like vectors. Let S_1, S_2 and S_3 be coordinate systems. If S_1 rotates with $\boldsymbol{\omega}_{1,2}$ with respect to S_2, and S_2 rotates with $\boldsymbol{\omega}_{2,3}$ with respect to S_3, then S_1 rotates instantaneously with respect to S_3 at:

$$\boldsymbol{\omega}_{1,3} = \boldsymbol{\omega}_{1,2} + \boldsymbol{\omega}_{2,3}$$

2.10.2 Angular Momentum

$$\boldsymbol{L} = \int \boldsymbol{r} \times (\boldsymbol{\omega} \times \boldsymbol{r})dm$$
$$= \mathbf{I}\boldsymbol{\omega}$$

$\mathbf{I}$ is the moment of inertia tensor:

$$\begin{pmatrix} \int(y^2+z^2) & -\int xy & -\int zx \\ -\int xy & \int(z^2+x^2) & -\int yz \\ -\int zx & -\int yz & \int(x^2+y^2) \end{pmatrix}$$

The kinetic energy of the object is given by:

$$T = \int \frac{1}{2}||\boldsymbol{\omega} \times \boldsymbol{r}||^2 dm$$
$$= \frac{1}{2}\boldsymbol{\omega} \cdot \mathbf{I}\boldsymbol{\omega} = \frac{1}{2}\boldsymbol{\omega} \cdot \boldsymbol{L}$$

To find the angular momentum for an object of mass M in general motion, let the position of its center of mass be $\boldsymbol{R}$, its velocity be $\boldsymbol{V}$. Then:

$$\boldsymbol{L} = M(\boldsymbol{R} \times \boldsymbol{V}) + \boldsymbol{L}_{\text{CM}}$$

The kinetic energy of the object is:

$$T = \frac{1}{2}MV^2 + \frac{1}{2}\boldsymbol{\omega}'\boldsymbol{L}_{\text{CM}}$$

Where $\boldsymbol{\omega}'$ and $\boldsymbol{L}_{\text{CM}}$ are measured about the center of mass along axes parallel to the fixed-frame axes.

2.10.3 Principal Axes

A principal axis is an axis of rotation $\hat{\boldsymbol{\omega}}$ such that $\mathbf{I}\hat{\boldsymbol{\omega}} = I\hat{\boldsymbol{\omega}}$. An object can rotate about a principal axis at constant angular velocity with no external torque. An orthonormal set of principle axis exists for every object.

3 Special Relativity

3.1 Postulates

1. The speed of light has the same value in all inertial frames
2. Physical laws remain the same in all inertial frames

3.2 Kinematics

3.2.1 Lorentz Transform

$$x = \gamma(x' + \beta ct')$$
$$y = y'$$
$$z = z'$$
$$ct = \gamma(\beta x' + ct')$$

Where $\gamma = \frac{1}{\sqrt{1-\frac{v^2}{c^2}}}$ and $\beta = \frac{v}{c}$.

3.2.2 Fundamental Effects

Length contraction

$$l' = \frac{l}{\gamma}$$

Where l is the proper length.

Time dilation

$$t' = \gamma t$$

Where t is the proper time.

Loss of simultaneity

$$\Delta t = \frac{Lv}{c^2}$$

Two events separated by L and Δt in the rest frame will appear simultaneous to an observer moving at v.

Longitudinal velocity addition

$$v'_x = \frac{u+v}{1+uv/c^2}$$

Where u is the velocity of an object in the frame traveling at v respect to the lab frame, and v'_x is the x-velocity of the object viewed by the lab frame.

Transverse velocity addition

$$v'_y = \frac{u_y}{\gamma_v(1+u_x v/c^2)}$$

Where u_y and u_x are velocity components of an object in the frame traveling at v respect to the lab frame, and v'_y is the y-velocity of the object viewed by the lab frame.

Longitudinal Doppler effect

$$f' = f\sqrt{\frac{1+\beta}{1-\beta}}$$

Where f' is the frequency observed of a moving source emitting at frequency f in its rest frame.

3.2.3 Minkowski Diagrams

Space-time diagrams with x and ct axes. Some properties are:

1. Light travels at 45° to horizontal.
2. x' and ct' axes of another moving frame are θ to the x and ct axes respectively, with

$$\tan(\theta) = \beta$$

3. Units on axes of the moving and stationary frames are related by:

$$\frac{x'}{x} = \frac{ct'}{ct} = \sqrt{\frac{1+\beta^2}{1-\beta^2}}$$

3.3 Dynamics

3.3.1 Momentum

$$\boldsymbol{p} = \gamma_v m\boldsymbol{v} = \frac{m\boldsymbol{v}}{\sqrt{1-\frac{v^2}{c^2}}}$$

3.3.2 Energy

$$E^2 = p^2c^2 + m^2c^4$$

For massive particles:

$$E = \gamma mc^2 = \frac{mc^2}{\sqrt{1-\frac{v^2}{c^2}}}$$

For massless particles(such as photons):

$$E = pc = \frac{hc}{\lambda}$$

3.4 4-vectors

A 4-vector $\vec{A} = (A_1, A_2, A_3, A_4)$ is a quantity that transforms as follows:

$$\begin{aligned} A'_1 &= \gamma(A_1 + i\beta A_4) \\ A'_2 &= A_2 \\ A'_3 &= A_3 \\ A'_4 &= \gamma(A_4 - i\beta A_1) \end{aligned}$$

The dot product of two 4-vectors is invariant under Lorentz transformations:

$$\vec{A}\cdot\vec{B} = \vec{A}'\cdot\vec{B}'$$

3.4.1 Different 4-vectors

4-position $(dx, dy, dz, icdt)$

4-vectors originate from the invariant interval ds.

$$\begin{aligned} \vec{ds}^{\,2} &= (dx, dy, dz, icdt)^2 \\ &= dx^2 + dy^2 + dz^2 - c^2dt^2 \end{aligned}$$

4-velocity $\gamma_v(\boldsymbol{v}, ic)$

To obtain other 4-vectors, we can multiply invariant quantities to the 4-position vector, such as proper time:

$$\begin{aligned} d\tau &= \frac{dt}{\gamma} \\ \vec{v} &= \frac{ds}{d\tau} \\ &= \gamma_v\left(\frac{dx}{dt}, \frac{dy}{dt}, \frac{dz}{dt}, ic\right) \\ &= \gamma_v(\boldsymbol{v}, ic) \end{aligned}$$

4-momentum $(\boldsymbol{p}, i\frac{E}{c})$

As mass is invariant,

$$\begin{aligned} \vec{p} &= m\vec{v} \\ &= (\gamma_v m\boldsymbol{v}, i\gamma_v mc) \\ &= \left(\boldsymbol{p}, i\frac{E}{c}\right) \end{aligned}$$

For photons in x-direction, the 4-momentum vector is:

$$\vec{p} = \left(\frac{h}{\lambda}, 0, 0, i\frac{h}{\lambda}\right)$$

4-wave $(\boldsymbol{k}, i\frac{\omega}{c})$

For electromagnetic waves,

$$\begin{aligned} k &= \frac{2\pi}{\lambda} = \frac{\omega}{c} \\ \boldsymbol{p} &= \frac{h}{\lambda} = \hbar\boldsymbol{k} \\ E &= hf = \hbar\omega \\ \vec{p} &= \hbar\left(\boldsymbol{k}, i\frac{\omega}{c}\right) \\ \vec{k} &= \frac{\vec{p}}{\hbar} \end{aligned}$$

4-force $\gamma_v\left(\boldsymbol{f}, \frac{i}{c}\frac{dE}{dt}\right)$

$$\begin{aligned} \vec{F} &= \frac{d\vec{p}}{d\tau} \\ &= \gamma_v\left(\boldsymbol{f}, \frac{d}{dt}\left(i\frac{E}{c}\right)\right) \end{aligned}$$

4 Electricity and Magnetism

4.1 Electrostatics

Coulomb's law The force between a point charge q and test charge Q:

$$\boldsymbol{F} = \frac{1}{4\pi\epsilon_0}\frac{Qq}{\mathrm{r}^2}\hat{\mathbf{r}}$$

Where $\mathbf{r} = \boldsymbol{r} - \boldsymbol{r'}$ is the displacement vector from Q at $\boldsymbol{r}$ and q at $\boldsymbol{r'}$.

Superposition principle The interaction between any two charges is unaffected by any other charges

4.1.1 Electric Field

The electric field of a point charge is defined as:

$$\boldsymbol{E} = \frac{\boldsymbol{F}}{Q} = \frac{1}{4\pi\epsilon_0}\frac{q}{\mathrm{r}^2}\hat{\mathbf{r}}$$

For a continuous volume charge distribution $\rho(\boldsymbol{r'})$, we can use the superposition principle to get:

$$\boldsymbol{E}(\boldsymbol{r}) = \frac{1}{4\pi\epsilon_0}\int_{\mathcal{V}}\frac{\rho(\boldsymbol{r'})}{\mathrm{r}^2}\hat{\mathbf{r}}d\tau'$$

Taking the divergence of $\boldsymbol{E}$, we get Gauss' law:

$$\boldsymbol{\nabla}\cdot\boldsymbol{E} = \frac{\rho(\boldsymbol{r})}{\epsilon_0}$$
$$\oint_{\mathcal{S}}\boldsymbol{E}\cdot d\boldsymbol{a} = \frac{Q_{\text{enc}}}{\epsilon_0}$$

Taking the curl of $\boldsymbol{E}$:

$$\boldsymbol{\nabla}\times\boldsymbol{E} = 0$$
$$\oint\boldsymbol{E}\cdot d\boldsymbol{l} = 0$$

For any surface charge in an electric field $\boldsymbol{E}$, the field felt by an area element on the surface is:

$$\boldsymbol{E}_{\text{felt}} = \frac{1}{2}\left(\boldsymbol{E}_{\text{above}} + \boldsymbol{E}_{\text{below}}\right)$$

4.1.2 Electric Potential

As the line integral of the electrostatic field is path independent, we can define the potential at a point $\boldsymbol{r}$:

$$V(\boldsymbol{r}) = -\int_{\mathcal{O}}^{\boldsymbol{r}}\boldsymbol{E}\cdot d\boldsymbol{l}$$

Where $\mathcal{O}$ is a standard reference point, usually set to infinity. The potential of a point charge can then be found, and with the superposition principle we can find the potential of any charge distribution:

$$V = \frac{1}{4\pi\epsilon_0}\frac{q}{\mathrm{r}}$$
$$V(\boldsymbol{r}) = \frac{1}{4\pi\epsilon_0}\int_{\mathcal{V}}\frac{\rho(\boldsymbol{r'})}{\mathrm{r}}d\tau'$$

Taking the gradient of the potential:

$$\boldsymbol{E} = -\nabla V$$
$$\nabla^2 V = -\frac{\rho}{\epsilon_0}$$

4.1.3 Work and Energy

The work needed to bring a charge Q from infinity to a point $\boldsymbol{a}$ is:

$$\begin{aligned} W &= \int_{\infty}^{\boldsymbol{a}}\boldsymbol{F}\cdot d\boldsymbol{l} \\ &= -Q\int_{\infty}^{\boldsymbol{a}}\boldsymbol{E}\cdot d\boldsymbol{l} \\ &= QV(\boldsymbol{a}) \end{aligned}$$

The energy in a continuous charge distribution is:

$$\begin{aligned} W &= \frac{1}{2}\int\rho V d\tau \\ &= \frac{\epsilon}{2}\int E^2 d\tau \end{aligned}$$

Where the integral is taken over all space.

4.1.4 Conductors

A perfect conductor has an unlimited supply of free charges.

1. $\boldsymbol{E} = 0$ and $\rho = 0$ inside a conductor
2. Any conductor is an equipotential
3. Just outside a conductor, $\boldsymbol{E}$ is perpendicular to the surface.

If we charge up two conductors with $+Q$ and $-Q$, the potential between them is proportional to the charge Q (because the electric field is proportional to Q), and we define the constant of proportionality capacitance:

$$C = \frac{Q}{V}$$

The work done by charging a capacitor is:

$$\begin{aligned} W &= \int_0^Q \frac{q}{C}dq = \frac{Q^2}{2C} \\ &= \frac{1}{2}CV^2 \end{aligned}$$

4.1.5 Image Charges

In certain special cases, a charge placed next to a grounded conductor has equivalents.

1. A point charge and a conducting sheet: An opposite charge in the mirror image position.
2. A point charge and a conducting sphere, or an infinite line charge and conducting cylinder: Opposite image charge and charge forms the Apollonius sphere/cylinder.

4.1.6 Uniqueness Theorems

First uniqueness theorem The solution to Laplace's equation ($\nabla^2 V = 0$) in some volume $\mathcal{V}$ is uniquely determined if V is specified on the boundary surface $\mathcal{S}$.

Second uniqueness theorem In a volume $\mathcal{V}$ surrounded by conductors and containing a specified charge density ρ, the electric field is uniquely determined if the total charge on each conductor is given.

4.2 Magnetostatics

4.2.1 Lorentz Force Law

The force felt by:

1. A point charge q moving at velocity $\boldsymbol{v}$ through a magnetic field $\boldsymbol{B}$:
$$\boldsymbol{F} = q\boldsymbol{v}\times\boldsymbol{B}$$
2. A line current $\boldsymbol{I}$:
$$\boldsymbol{F} = I\int(d\boldsymbol{l}\times\boldsymbol{B})$$
3. A general volume current $\boldsymbol{J}$ per unit area perpendicular to flow:
$$\boldsymbol{F} = \int(\boldsymbol{J}\times\boldsymbol{B})d\tau$$

4.2.2 Biot-Savart Law

The magnetic field created by a steady line current:

$$\boldsymbol{B}(\boldsymbol{r}) = \frac{\mu_0}{4\pi}I\int\frac{d\boldsymbol{l}\times\hat{\mathbf{r}}}{\mathrm{r}^2}$$

4.2.3 Magnetic Fields

The magnetic field is divergence-free:

$$\nabla \cdot \boldsymbol{B} = 0$$
$$\oint \boldsymbol{B} \cdot d\boldsymbol{a} = 0$$

Taking the curl of the magnetic field gives Ampere's Law:

$$\nabla \times \boldsymbol{B} = \mu_0 \boldsymbol{J}$$
$$\oint \boldsymbol{B} \cdot d\boldsymbol{l} = \mu_0 I_{\text{enc}}$$

4.3 Electrodynamics

4.3.1 Electromotive Force

For an electric field applied in a material:

$$\boldsymbol{J} = \frac{\boldsymbol{E}}{\rho}$$

Where ρ is the resistivity constant depending on the material. This leads to Ohm's law:

$$V = IR$$
$$R = \rho \frac{l}{A}$$

The power delivered:

$$P = VI = I^2 R$$

The electromotive force (emf) $\mathcal{E}$ is the line integral of the force per unit charge driving the current:

$$\mathcal{E} = \oint \boldsymbol{E} \cdot d\boldsymbol{l}$$

$\mathcal{E} = V$ for an ideal source.

4.3.2 Faraday's Law

Faraday's law states that a changing magnetic flux Φ induces an electric field:

$$\mathcal{E} = \oint \boldsymbol{E} \cdot d\boldsymbol{l} = \frac{d\Phi}{dt}$$
$$\nabla \times \boldsymbol{E} = \frac{d\boldsymbol{B}}{dt}$$

4.3.3 Inductance

If we have two current loops 1 and 2, the flux Φ_2 through loop 2 is proportional to the current through loop 1:

$$\Phi_2 = M_{21} I_1$$

Where $M_{21} = M_{12}$ is the mutual inductance between these two loops. We can also define an self inductance L, for a single loop:

$$\Phi = LI$$
$$\mathcal{E} = -L\frac{dI}{dt}$$

4.4 Electric Circuits

5 Oscillations and Waves

Many questions involve solving linear differential equations. For such equations, linear combinations of solutions will also be a solution.

5.1 Oscillations

5.1.1 Simple Harmonic Motion

We have a spring force, $F = -kx$.

$$\ddot{x} + \omega^2 x = 0, \text{ where } \omega = \sqrt{\frac{k}{m}}$$
$$x(t) = A\cos(\omega t + \phi)$$

5.1.2 Damped Oscillators

In addition to the spring force, we now have a drag force $F_f = -bv$, and the total force $F = -kx - b\dot{x}$.

$$\ddot{x} + 2\gamma\dot{x} + \omega^2 x = 0$$

Where $2\gamma = b/m$ and $\omega^2 = k/m$. Let $\Omega = \sqrt{\gamma^2 - \omega^2}$.

$$x(t) = e^{-\gamma t}(Ae^{\Omega t} + Be^{-\Omega t})$$

Underdamping $(\Omega^2 < 0)$

$$x(t) = e^{-\gamma t}(Ae^{i\tilde{\omega}t} + Be^{-i\tilde{\omega}t})$$
$$= e^{-\gamma t} C\cos(\tilde{\omega}t + \phi)$$

Where $\tilde{\omega} = \sqrt{\omega^2 - \gamma^2}$. The system will oscillate with its amplitude decreasing over time. The frequency of oscillations will be smaller than in the undamped case.

Overdamping $(\Omega^2 > 0)$

$$x(t) = Ae^{-(\gamma-\Omega)t} + Be^{-(\gamma+\Omega)t}$$

The system will not oscillate, and the motion will go to zero for large t.

Critical damping $(\Omega^2 = 0)$

We have $\gamma = \omega$, and:

$$\ddot{x} + 2\gamma\dot{x} + \gamma^2 x = 0$$

In this special case, $x = te^{-\gamma t}$ is also a solution:

$$x(t) = e^{-\gamma t}(A + Bt)$$

Systems with critical damping go to zero the quickest.

5.1.3 Driven Oscillators

We have to solve differential equations of this form:

$$\ddot{x} + 2\gamma\dot{x} + ax = \sum_{n=1}^{N} C_n e^{i\omega_n t}$$

We first find particular solutions for each n, by guessing solutions of the form $x_{p_n}(t) = Ae^{i\omega_n t}$:

$$-A{\omega_n}^2 + 2iA\gamma\omega_n + Aa = C_n$$
$$x_{p_n}(t) = \frac{C_n}{-{\omega_n}^2 + 2i\gamma\omega_n + a} e^{i\omega_n t}$$

Using the superposition principle, the final solution is a linear combination of the general solution and the particular solutions, with the combination constants determined by initial conditions.

5.1.4 Coupled Oscillators

Normal modes are states of a system where all parts are moving with the same frequency. General strategy to find normal modes:

1. Write down the n equations of motions corresponding to the n degrees of freedom the system has.
2. Substitute $x_i = A_i e^{i\omega t}$ into the differential equations to get a system of linear equations in A_i, with $i = 1, 2, \cdots, n$
3. Non-trivial solutions exist if and only if the determinant of the matrix is zero. Solve for ω, and subsequently find A_i

The motion of the system can then be decomposed into linear combinations of its normal modes.

5.1.5 Small Oscillations

For an object at a local minimum of a potential well, we can expand $V(x)$ about the equilibrium point:

$$V(x) = V(x_0) + V'(x_0)(x - x_0) + \frac{1}{2!}V''(x_0)(x - x_0)^2 + \cdots$$

As $V(x_0)$ is an additive constant, and $V'(x_0) = 0$ by definition of equilibrium,

$$V(x) \approx \frac{1}{2}V''(x_0)(x - x_0)^2$$
$$F = -\frac{dV}{dx} = -V''(x_0)(x - x_0)$$
$$\omega = \sqrt{\frac{V''(x_0)}{m}}$$

5.2 Wave Equation

A wave is a disturbance of a continuous medium that propagates with a fixed shape at constant velocity. In one dimension:

$$f(z,t) = f(z - vt, 0) = g(z - vt)$$

All such functions f are the solutions to the wave equation:

$$\frac{\partial^2 f}{\partial x^2} = \frac{1}{v^2}\frac{\partial^2 f}{\partial t^2}$$

Where v is the speed of propagation.

5.2.1 Electromagnetic Waves

6 Optics

6.1 Geometric Optics

Results from Fermat's principle of least time:

$$\theta_{\text{incidence}} = \theta_{\text{reflection}}$$
$$n_1 \sin\theta_1 = n_2 \sin\theta_2$$

Sign convention:

- Light rays travel from left to right
- f is positive if surface makes rays more convergent
- Distances are measured from the surface (left is negative)
- s_o is negative for real objects
- s_i is positive for real images
- y above optical axis is positive

$$\frac{1}{f} = \frac{1}{s_i} + \frac{1}{s_o}$$
$$M = \frac{y_i}{y_o} = -\frac{s_i}{s_o}$$

For thin lenses and mirrors:

$$\frac{1}{f} = \frac{2}{R}$$

For composite thin lenses:

$$\frac{1}{f} = (n-1)\left(\frac{1}{R_1} + \frac{1}{R_2}\right)$$

Lens formed by interface of two materials with different n:

$$\frac{n_2 - n_1}{R} = \frac{n_2}{s_i} + \frac{n_1}{s_o}$$

6.2 Polarization

For polarized light:

$$E = E_0 \cos\theta$$
$$I = I_0 \cos^2\theta$$

For unpolarized light:

$$\langle I \rangle = I_0 \langle \cos^2\theta \rangle = \frac{I_0}{2}$$

Brewster angle at which all reflected light at an interface is polarized:

$$\tan\theta_i = \frac{n_t}{n_i}$$

6.3 Physical Optics

Interference is the superposition of wave amplitudes when waves overlap.

6.3.1 Double Slit:

Occurs when slits are of negligible width, distance between slits comparable to wavelength, such that diffraction effects are insignificant. For bright fringes:

$$d\sin\theta = m\lambda$$
$$y_m = R\frac{m\lambda}{d} \qquad m \in \mathbb{Z}$$

For incident medium's refractive index n_i, reflection medium's refractive index n_r, if $n_i < n_r$, the reflected wave undergoes a $\frac{\pi}{2}$ phase shift.

6.3.2 Single Slit:

Occurs when size of slit is comparable to wavelength. Location of dark fringes when wavelets at distance $\frac{a}{2}$ destructively interfere:

$$\sin\theta = \frac{m\lambda}{d}$$
$$y_m = x\frac{m\lambda}{a} \qquad m \in \mathbb{Z}$$

6.3.3 Intensity in Diffraction Patterns

For double slit interference:

$$I = I_{\max}\cos^2\left(\frac{\pi d \sin\theta}{\lambda}\right)$$

For single slit diffraction:

$$I = I_{\max}\left[\frac{\sin(\pi a \sin\theta/\lambda)}{\pi a \sin\theta/\lambda}\right]^2$$

Double slit including effects of diffraction:

$$I = I_{\max}\cos^2\left(\frac{\pi d \sin\theta}{\lambda}\right) \cdot \left[\frac{\sin(\pi a \sin\theta/\lambda)}{\pi a \sin\theta/\lambda}\right]^2$$

7 Thermodynamics

8 Quantum Mechanics

8.1 Schrödinger's Equation

$\Psi(x,t)$ is a complex wave function of time and position, the one-dimensional Schrödinger's equation is given by:

$$i\hbar\frac{\partial\Psi}{\partial t} = -\frac{\hbar^2}{2m}\frac{\partial^2\Psi}{\partial x^2} + V\Psi$$

If we denote the complex conjugate of the wave function to be Ψ^*, the conjugate of Schrödinger's equation is:

$$-i\hbar\frac{\partial\Psi^*}{\partial t} = \frac{\hbar^2}{2m}\frac{\partial^2\Psi^*}{\partial x^2} - V\Psi^*$$

At time t, the probability of finding a particle from $x = a$ to $x = b$ is:

$$\int_a^b |\Psi(x,t)|^2 dx = \int_a^b \Psi\Psi^* dx$$

8.1.1 Normalization

All wave functions must be normalized, so that the probability of finding the particle over all space is 1:

$$\int_{-\infty}^{\infty} |\Psi(x,t)|^2 dx = 1$$

Once a function is normalized, it remains normalized as time evolves:

$$\frac{d}{dt}\int_{-\infty}^{\infty} \Psi\Psi^* = 0$$

8.1.2 Expectation Values

An expectation value of an observed quantity is the average of the measurement performed on many "copies" of the system at the same time.

$$\begin{aligned}
\langle x\rangle &= \int_{-\infty}^{\infty} x|\Psi(x,t)|^2 dx \\
&= \int_{-\infty}^{\infty} \Psi^* x \Psi dx \\
\langle p\rangle &= m\frac{d\langle x\rangle}{dt} \\
&= \int_{-\infty}^{\infty} \Psi^* \left(-i\hbar\frac{\partial}{\partial x}\right)\Psi dx
\end{aligned}$$

In general, the expectation value of any quantity is:

$$\langle Q(x,p)\rangle = \int \Psi^* Q\left(x, -i\hbar\frac{\partial}{\partial x}\right)\Psi dx$$

8.2 Time Independent Solution

We solve Schrödinger's equation by separation of variables. Let:

$$\Psi(x,t) = \psi(x)\phi(t)$$

Then the equation can be written as:

$$\begin{aligned}
i\hbar\psi\frac{\partial\phi}{\partial t} &= -\frac{\hbar^2}{2m}\frac{\partial^2\psi}{\partial x^2}\phi + V\phi\psi \\
\left(\frac{i\hbar}{\phi}\frac{\partial\phi}{\partial t}\right) + \left(\frac{\hbar^2}{2m\psi}\frac{\partial^2\psi}{\partial x^2} - V(x)\right) &= 0
\end{aligned}$$

As the two terms in the equation are independent of each other and they sum to zero, they must be constant. If we let:

$$\begin{aligned}
E &= \frac{i\hbar}{\phi}\frac{\partial\phi}{\partial t} \\
\phi(t) &= e^{iE/\hbar t}
\end{aligned}$$

The time independent solution is given by:

$$-\frac{\hbar^2}{2m}\frac{\partial^2\psi}{\partial x^2} + V(x)\psi = E\psi$$

If we define the Hamiltonian operator $\hat{\mathrm{H}} = -\frac{\hbar^2}{2m}\frac{\partial^2}{\partial x^2} + V$:

$$\hat{\mathrm{H}}\psi = E\psi$$