$x = x_0 + v_{x_0}t + \frac{1}{2}a_xt^2$ $v_x^2 = v_{x_0}^2 + 2a_x (x - x_0)$ $\overline{a} = \frac{\sum \overline{F}}{m} = \frac{\overline{F}_{mt}}{m}$ $ \overline{F}_T  \leq \mu  \overline{F}_n $ $a_z = \frac{v^2}{r}$ $\overline{p} - mv$ $\Delta \overline{p} = \overline{F}\Delta t$ $K = \frac{1}{2}mv^2$ $\Delta F = W - F_d = F d \cos 0$ $F = \frac{\Delta F}{\Delta t}$ $\Theta = \Theta_0 + \Theta_0 t + \frac{1}{2}at^2$ $\Theta = \Theta_0 + at$ $x = A \cos(\omega t) = A \cos(2\pi t)$ $x_{tm} = \frac{\sum m_{tx_t}}{\sum m_t}$ $\overline{a} - \frac{\sum \overline{1}}{t} - \frac{\overline{1}_{mt}}{t}$ $\overline{a} = x_t = x_t$ $L = angular momentum F = \text{rotational inertia} K = \text{spring constant} L = \text{angular momentum} E = \text{length} m = \text{mass} E = \text{power} E = \text{position} E = \text$	$v_x = v_{x_0} + a_x t$	a = acceleration
$v_x^2 = v_{k_0}^2 + 2a_x (x - x_0)$ $= -\frac{\sum F}{m} - \frac{F_{mt}}{m}$ $ F_f  \leq \mu  F_n $ $a_e = \frac{v^2}{r}$ $= -mv$ $ A_f  = F \land r $ $= -mv$ $ A_f  = \frac{1}{2}mv^2$ $\Delta E = W = F_0 d = F d \cos \theta$ $ B_f  = \frac{\Delta E}{\Delta r}$ $ B_f  = $		A = amplitude
$v_x^2 = v_{k_0}^2 + 2a_x (x - x_0)$ $= -\frac{\sum F}{m} - \frac{F_{mt}}{m}$ $ F_f  \leq \mu  F_n $ $a_e = \frac{v^2}{r}$ $= -mv$ $ A_f  = F \land r $ $= -mv$ $ A_f  = \frac{1}{2}mv^2$ $\Delta E = W = F_0 d = F d \cos \theta$ $ B_f  = \frac{\Delta E}{\Delta r}$ $ B_f  = $	$x = x_0 + v_{x_0}t + \frac{1}{2}a_xt^2$	d = distance
$ F_{-T}  = \frac{F_{-T}}{m}$ $ F_{-T}  \leq \mu  F_{-T} $ $ F_{-T}  = \mu  F_{-T} $ $ F$	$v_x^2 = v_{x_0}^2 + 2a_x(x - x_0)$	
$ F_f  \leq \mu  F_n $ $ F_f  = m  F_n $ $ F_f  = m $	$-\sum \overrightarrow{F} = \overrightarrow{F}_{rest}$	
$ F_f  \leq \mu  F_n $ $a_s = \frac{y^2}{r}$ $P = mv$ $\Delta P = F\Delta t$ $E = \frac{1}{2}mv^2$ $\Delta E = W = F_0 d = F d \cos \theta$ $E = \frac{\Delta E}{\Delta t}$ $\Theta = \Theta_0 + \Theta_0 t + \frac{1}{2}at^2$ $E = A \cos(\omega t) = A \cos(2\pi t)$ $E = \frac{\Sigma m_i x_i}{T}$ $E = r_\perp F = rF \sin \theta$ $E = \frac{1}{2}I\omega^2$ $\Delta L = t\Delta t$ $E = r_\perp F = rF \sin \theta$ $E = \frac{1}{2}I\omega^2$	$a = \frac{1}{2} = \frac{1}{2}$	
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$a_{c} = \frac{V}{r}$ $\overline{p} = m\overline{V}$ $\Delta \overline{p} = \overline{F}\Delta t$ $K = \frac{1}{2}mV^{2}$ $\Delta E = W = F_{\parallel}d = Fd\cos\theta$ $F = \frac{\Delta E}{\Delta t}$ $\theta = \theta_{0} + \omega_{0}t + \frac{1}{2}at^{2}$ $\omega = \omega_{0} + at$ $x = A\cos(\omega t) = A\cos(2\pi t)$ $\overline{\alpha} = \frac{\overline{\Sigma} m_{t}x_{t}}{\overline{\Sigma} m_{t}}$ $\overline{\alpha} = \frac{\overline{\Sigma} T}{I} = \frac{\overline{T}_{tot}}{I}$ $\tau = r_{\perp}F = rF\sin\theta$ $L = I\omega$ $\Delta L = \tau\Delta t$ $K = \frac{1}{2}I\omega^{2}$ $\overline{F}_{z} = k \overline{x} $ $U_{z} = \frac{1}{2}kx^{2}$ $\theta = \theta_{0} + \omega_{0}t + \frac{1}{2}at^{2}$ $\omega = \omega_{0} + at$ $x = A\cos(\omega t) = A\cos(2\pi t)$ $T = \cos(t)$ $T = \cos(t)$ $T = \cos(t)$ $T = \cos(t)$ $T = \sin(t)$ $T = \cos(t)$ $T = \sin(t)$	$ F_{\mathcal{F}}  \leq \mu  F_n $	
$\begin{array}{ll} \overline{p} = mv \\ \Delta \overline{p} = \overline{F}\Delta t \\ K = \frac{1}{2}mv^2 \\ \Delta E = W = F_d = Fd\cos\theta \\ P = \frac{\Delta E}{\Delta t} \\ \Theta = \Theta_0 + \Theta_0 t + \frac{1}{2}at^2 \\ \Sigma = A\cos(\omega t) = A\cos(2\pi t) \\ \Sigma_{cm} = \frac{\sum m_i x_i}{\sum m_i} \\ \overline{x} = r_2 F = rF\sin\theta \\ L = I\omega \\ \Delta L = \Delta L \\ K = \frac{1}{2}I\omega^2 \\ \overline{F}_z = k \overline{x}  \\ U_z = \frac{F_z}{m_i} \\ \overline{F}_z = \frac{1}{2}\kappa x^2 \\ \end{array} \qquad \begin{array}{ll} m = \max \\ P = \text{power} \\ P = \text{momentum} \\ r = \text{radius or separation} \\ U = \text{potential energy} \\ V = \text{speed} \\ W = \text{work done on a system} \\ X = \text{position} \\ X = \text{angular acceleration} \\ \Theta = \text{angular acceleration} \\ \Theta = \text{angular speed} \\ T = \frac{2\pi}{\omega} = \frac{1}{f} \\ T = \frac{2\pi}{\omega} = \frac{\pi}{\omega} = \frac{\pi}{\omega} $	$v^2$	[ [ [ [ [ [ [ [ [ [ [ [ [ [ [ [ [ [ [
$\begin{array}{ll} \overline{p} = m\overline{\nu} \\ \Delta \overline{p} = F\Delta t \\ K = \frac{1}{2}m\nu^2 \\ \Delta E = W = F_0 d = F d \cos \theta \\ P = \frac{\Delta E}{\Delta t} \\ \theta = \theta_0 + \omega_0 t + \frac{1}{2}at^2 \\ \omega = \omega_0 + at \\ K = \frac{\Sigma m_i \kappa_i}{\Sigma m_i} \\ \overline{\alpha} = \frac{\Sigma T}{I} = \frac{\overline{\tau}_{nst}}{I} \\ \overline{\tau} = r_L F = rF \sin \theta \\ L = I\omega \\ L_s = \frac{1}{2}I\omega^2 \\ \overline{F}_s = k \overline{x}  \\ U_s = \frac{1}{2}\kappa\epsilon^2 \\ U_s = \frac{F}{m_s} \frac{\pi}{m_s} \\ \overline{F}_s = \frac{\overline{\tau}_{nst}}{I} $	$a_c = \frac{1}{a_c}$	$\ell =  ext{length}$
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$\begin{array}{ll} x = \operatorname{position} \\ \theta = \theta_0 + \omega_0 t + \frac{1}{2} a t^2 \\ \omega = \omega_0 + a t \\ x = A \cos (\omega t) = A \cos (2\pi f t) \\ x_{em} = \frac{\sum m_i x_i}{\sum m_i} \\ \overline{\alpha} = \frac{\sum \overline{T}}{I} = \frac{\overline{T}_{met}}{I} \\ \overline{\tau} = r_L F = r F \sin \theta \\ L = I \omega \\ \Delta L = \tau \Delta t \\ K = \frac{1}{2} I \omega^2 \\ U_s = \frac{1}{2} k c^2 \end{array} \qquad \begin{array}{ll} x = \operatorname{position} \\ y = \operatorname{height} \\ \alpha = \operatorname{angular} \operatorname{acceleration} \\ \mu = \operatorname{coefficient} \operatorname{of friction} \\ \theta = \operatorname{angle} \\ \rho = \operatorname{density} \\ \tau = \operatorname{torque} \\ \omega = \operatorname{angular} \operatorname{speed} \\ T = \frac{2\pi}{\omega} = \frac{1}{f} \\ T = \frac{2\pi}{\omega} = \frac{1}{f} \\ T = 2\pi \sqrt{\frac{m}{k}} \\ T_p = 2\pi \sqrt{\frac{\ell}{g}} \\  \overline{F}_s  = G \frac{m_1 m_2}{r^2} \\  \overline{F}_s  = G \frac{\overline{m_1 m_2}}{r^2} \\  \overline{F}_s  = G \frac{\overline{F}_s}{m} \end{array}$	$D = \Delta E$	
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$\begin{aligned}  \vec{F}_{\mathcal{S}}  &= k  \vec{x}  \\ U_{\mathcal{S}} &= \frac{1}{2} k x^{2} \end{aligned} \qquad \begin{aligned}  \vec{F}_{\mathcal{S}}  &= G \frac{m_{1} m_{2}}{r^{2}} \\ \vec{g} &= \frac{\vec{F}_{\mathcal{S}}}{m} \end{aligned}$	$r = 1 r_{co}^2$	$T_p = 2\pi \sqrt{\frac{g}{g}}$
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		$ \overline{F}_{s}$
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# **Physics Castle Section 2 Quiz**

Raffaela Di Napoli

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