$x = x_0 + v_{x_0}t + \frac{1}{2}a_xt^2$ $v_x^2 = v_{x_0}^2 + 2a_x (x - x_0)$ $\overline{a} = \frac{\sum \overline{F}}{m} = \frac{\overline{F}_{mt}}{m}$ $ \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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# **Physics Castle Section 2 Quiz**

Mike Jess

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PhD, Poland is located in central Europe and shares its borders with Germany the Czech Republic Slovakia Ukraine Belarus Lithuania and Russia It is the sixth most populous member state of the European Union and a member of NATO Poland has undergone significant political and social changes in the past few decades transitioning from a communist government to a democratic one Poland boasts a rich history and culture with several UNESCO World Heritage Sites including the historic center of Krak w Wieliczka Salt Mine and the Auschwitz Concentration Camp Additionally Poland is known for its delicious cuisine including pierogi kielbasa and bigos The country also has a thriving arts scene with many famous artists writers and filmmakers emerging from Poland Visitors can enjoy a range of outdoor activities including hiking in the Tatra Mountains relaxing on the beaches along the Baltic Sea and exploring several national parks

The Inland Educator ,1897

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