

Chapter 11 & 12 Study Guide: Motion & Forces Answer Key

Chapter 11: Motion

1. Define (include the formula and circle diagram for calculating speed, velocity, and acceleration):
 - a. Distance: The length between two objects or the length of the path traveled.
 - b. Speed: distance traveled by the time it took to travel. **speed = distance/time**
 - c. Velocity: distance traveled by the time it took to travel and the direction that you traveled in. **velocity = distance/time**
 - d. Acceleration: change in velocity or velocity over time. **acceleration = $\frac{velocity_{final} - velocity_{initial}}{time}$**
2. What is the speed of an object at rest? **0 m/s**
3. The difference between speed and velocity is that velocity includes **direction**.
4. The SI unit for distance is **meter (m)**.
5. The SI unit for speed or velocity is **meter per second (m/s)**.
6. The SI unit for acceleration is **meter per second squared (m/s²)**.
7. On a **distance-time** graph, what does the slope tell you? **Speed or Velocity**
8. On a **speed-time** graph, what does the slope tell you? **Acceleration**

Chapter 12: Forces

9. Describe (what does it say and what is it commonly called)
 - a. Newton's First law of Motion: **Also known as "Law of Inertia". Object in motion stays in motion and an object at rest stays at rest UNLESS acted upon by a NET FORCE.**
 - b. Newton's Second law of Motion: **$F = m \times a$. Force equals the product of an object's mass and acceleration. (Acceleration is equal to the force and inversely proportional to mass)**
 - c. Newton's Third law of Motion: **Also known as "Action/Reaction Law". For every action there is an equal and opposite reaction.**
10. Give **an example for each** of Newton's laws
 - a. Newton's First law of Motion: **boulder won't move unless something pushes on it, and the moon won't stop rotating unless a force acts on it.**
 - b. Newton's Second law of Motion: **it takes more force to accelerate a school bus than a toy car.**
 - c. Newton's Third law of Motion: **my foot pushed on the ball (action force), the ball pushes back (reaction force) and fly's forward (resulting net force). OR when you sit in the desk you push down on the desk and the desk pushes on you but they are balanced so there is NO CHANGE in motion.**
11. Define and give an example of each of the following terms.

Definition	Example
a. Friction: force that opposes motion.	a. Friction: heat when rubbing hands together.
b. Static Friction: friction that prevents object from moving.	b. Static Friction: pushing against a dresser that won't move.
c. Sliding Friction: friction that occurs between objects sliding past each other.	c. Sliding Friction: going down a slide; dresser sliding across the floor.
d. Rolling Friction: friction that occurs between object rolling against another object.	d. Rolling Friction: roller skates on pavement; car driving on the road
e. Fluid Friction: friction that occurs in a fluid (Examples of Fluid: water, quicksand, air.)	e. Fluid Friction: falling leaves; fish swimming in water

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web sep 2 2020 this work involves designing and fabricating a simple pick and place arm type robot that could be used in handling of parts during different production process the production process may include

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web fig 4 block diagram of mobile operated pick and place robot the main part of the project is mechanical arrangement of robot arm by using 3 motors we can develop the robot arm with help of 4 or 5 motors according to our design in this project we used only 3 motors for controlling robot arm the below diagram shows the robot arm arrangement

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web fig 1 block diagram of line follower robot fig 2 implemented line follower prototype model 2 pick and place robot the robotic arm is a type of mechanical arm which is usually programmable with similar functions to a human arm and human controlled based system the pick and place robotic arm consists of a robotic arm placed on a moving

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web design analysis of a remote controlled pick and place robotic vehicle 59 fig 1 block diagram of mode of operation 3 1 4 elbow this is the joint between links b and c and it has one degree of freedom actuated by a rc servo motor it can rotate to about 180° by design by link a the motion about the elbow is actuated by a set of gear trains

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web block diagram showing receiver of a pick n place robot the system consists of two motors for providing motion to the

whole robot and two other motors to provide the arm motion the end effector or the gripper needs to be controlled to apply proper pressure on the object to handle it effectively to give it a soft grip

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web dec 1 2017 the project is about utilizing four wheeled robot arduino uno microcontroller to create a pick and place robot that can do any pick and place function a radio frequency transmission fsi6 is

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web based on the user commands the robot moves and pick and place the objects the robotic arm used here is similar to a human arm which is programmed to perform the pick and place functions the remainder of this paper is organized as follows the section 2 provides information about the existing works section 3 gives details of the proposed

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web pick and place robot module block diagram 14 3 3 1 robotic arm design the robotic arm with gripper termination has five degrees of freedom with a rotating base that rests on the upper region of the vehicle as depicted in figure 6