Lecture 1
Tue. 8.22.2017

1st axioms and theorems of classical mechanics

(Ch. 1 thru Ch. 3 of Unit 1)

Geometry of momentum conservation axiom (ala Occam's Razor)
- *Totally Inelastic "ka-runch"collisions* (begin 4:1 graph project)*
- *Perfectly Elastic "ka-bong" and Center Of Momentum (COM) symmetry**
  - *+Intro to weighty-averages and vector notation*
- *Comments on idealization in classical models*

Geometry of Galilean translation symmetry
- *45° shift in (V_1,V_2)-space*
- *Time reversal symmetry*
- *...of COM collisions*

Algebra,Geometry, and Physics of momentum conservation axiom
- *Vector algebra of collisions*
- *Matrix or tensor algebra of collisions*
- *Deriving Energy Conservation Theorem*

Numerical details of collision tensor algebra

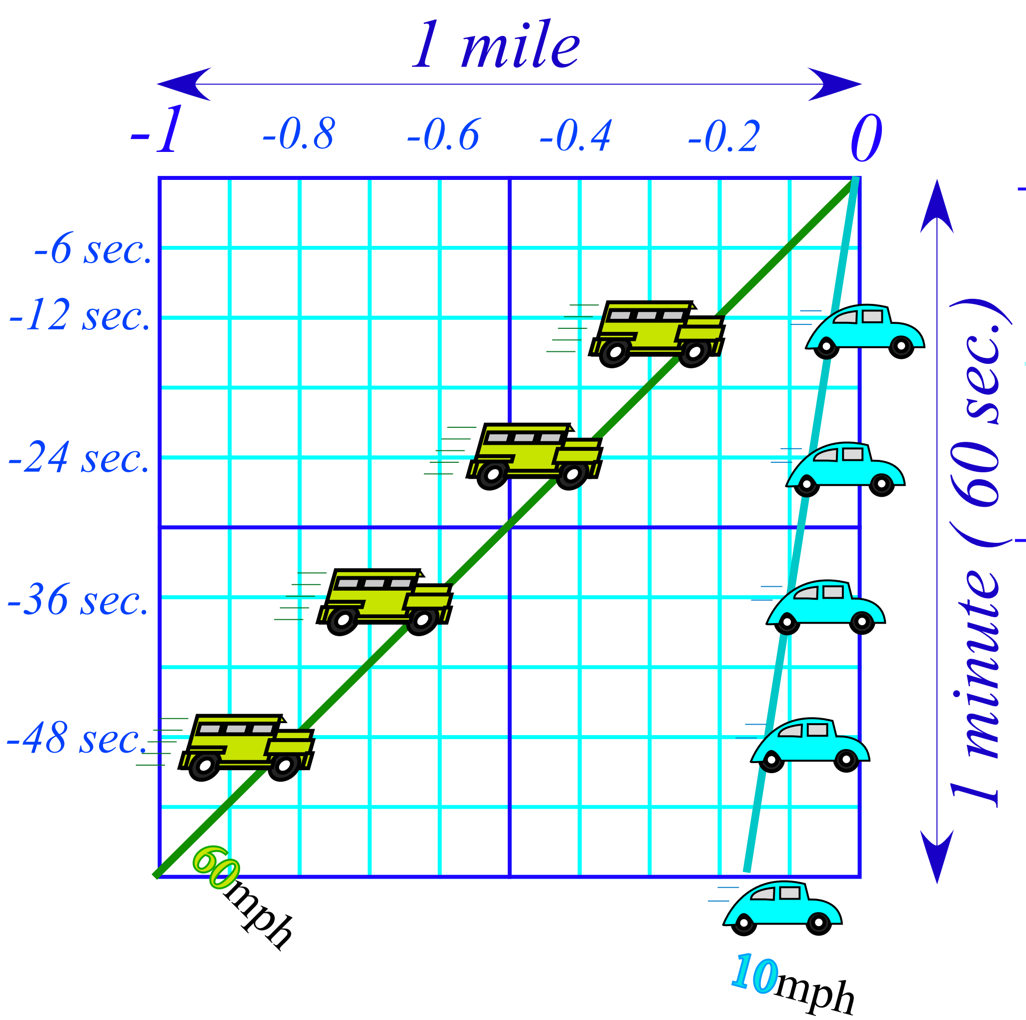
Note - Many of the underlined links throughout this lecture file link to the specific selected cases within those Web Simulators

**Launch Car Generic Collision Web Simulator* http://www.uark.edu/ua/modphys/markup/CMMotionWeb.html

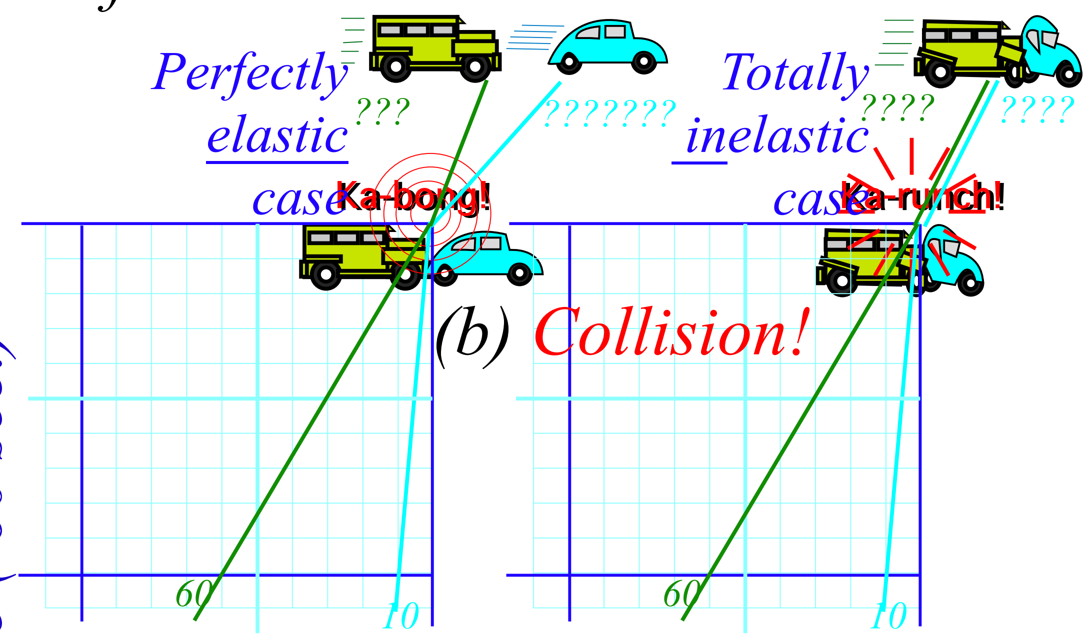
**Launch Generic Superball Collision Web Simulator* http://www.uark.edu/ua/modphys/markup/BounceItWeb.html

A problem in *space-time* : (60mph Cell-faxing 4ton SUV rear-ends 10mph 1ton VW)

Before collision.....



After collision...what velocities?



Car Simulator
Space vs Space
Elastic

Car Simulator
Space vs Space
Inelastic

Simulator
Elastic Collision
Dual Panel Space vs Space and Space vs Time (Newton)

Simulator
Inelastic Collision
Dual Panel Space vs Space and Space vs Time (Newton)

Simulator
Elastic Collision
Dual Panel Space vs Space and Time vs. Space(Minkowski)

Simulator
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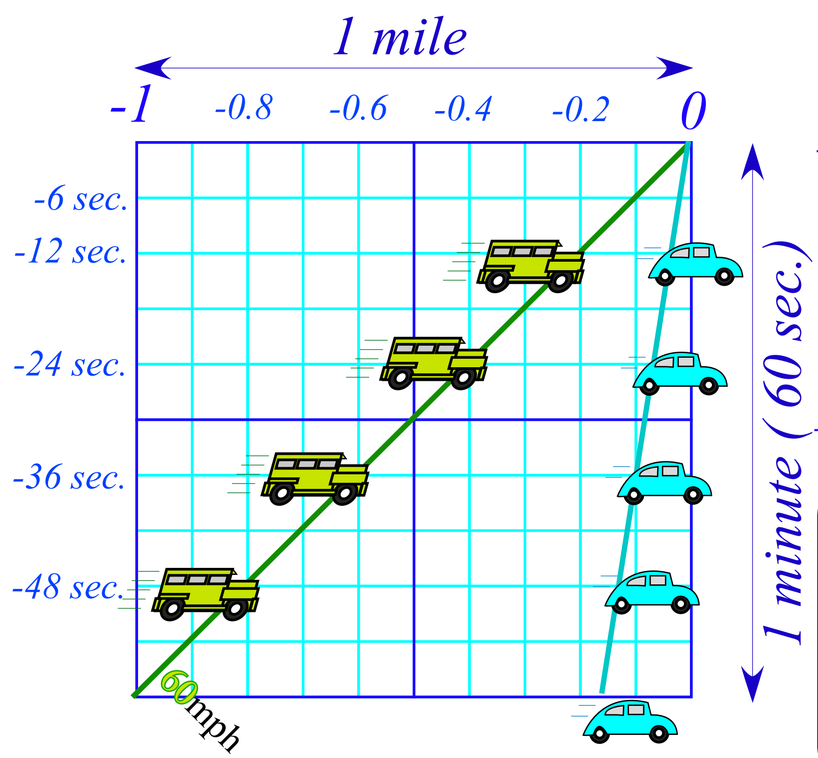
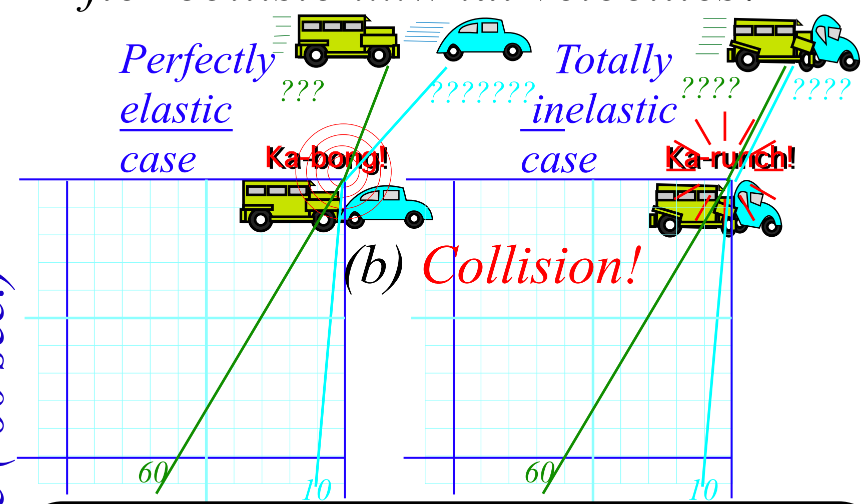
**Car Collision simulator http://www.uark.edu/ua/modphys/testing/markup/CMMotionWeb.html*

A problem in *space-time* : (60mph Cell-faxing 4ton SUV rear-ends 10mph 1ton VW)

Before collision.....



After collision...what velocities?



Conventional solution: Look up the usual momentum and energy formulas/axioms:

$\Sigma_i m V_i(\text{initial}) = \Sigma_i m V_i(\text{final})$

$\Sigma_i m V^2_i(\text{initial}) = \Sigma_i m V^2_i(\text{final})$

and solve...

Let's see if we can solve this *easily* with just ***one*** (*or one-and-a-half*) axiom(s)

Axiom-1: All mass or masses keep their total momentum until it is changed by some outsider.

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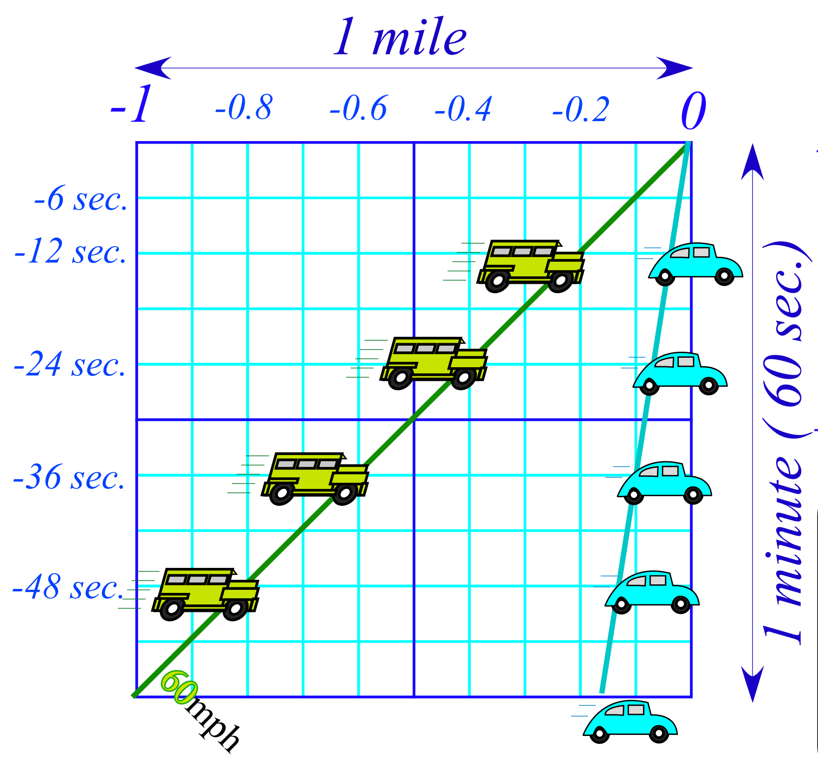
A problem in *space-time* : (60mph Cell-faxing 4ton SUV rear-ends 10mph 1ton VW)

Before collision.....



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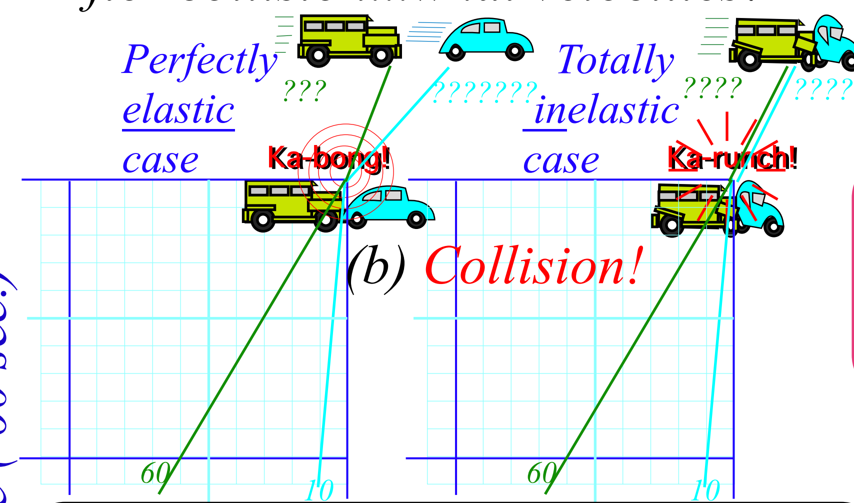

V_{SUV} and V_{VW} change <u>violently</u>
but NOT ***total momentum***

$P_{Total} = M_{SUV} V_{SUV} + M_{VW} V_{VW}$

Conventional solution: Look up the usual momentum and energy formulas/axioms:

$\Sigma_i m V_i(initial) = \Sigma_i m V_i(final)$

$\Sigma_i m V^2_i(initial) = \Sigma_i m V^2_i(final)$

and solve...

...But an UNconventional way is quicker and slicker.....
..... (Just have to draw 2 lines!)

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V_{SUV} and V_{VW} change violently
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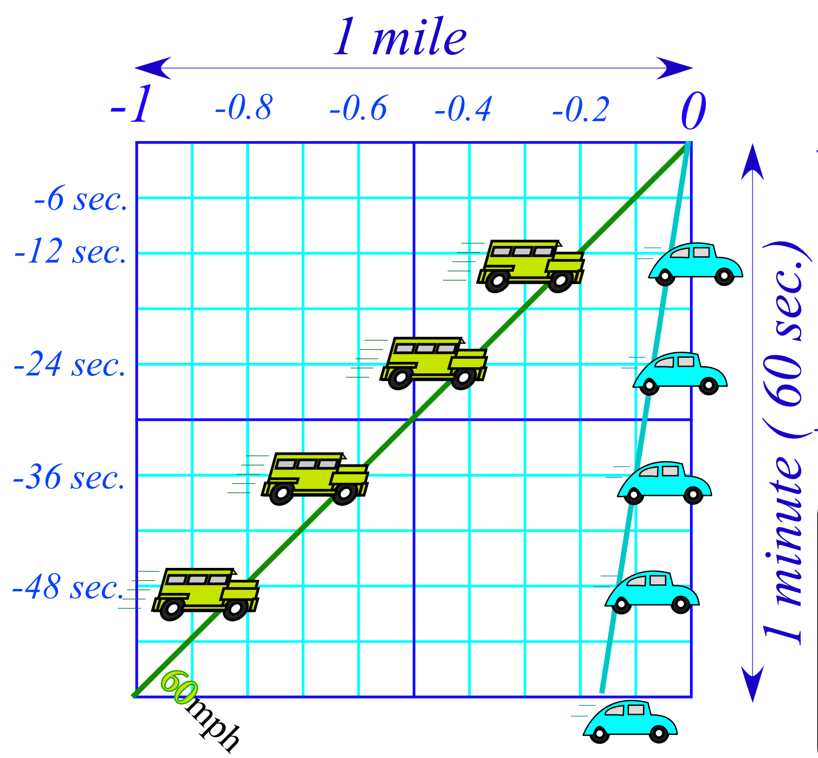
$P_{Total} = M_{SUV} V_{SUV} + M_{VW} V_{VW}$

Before collision.....



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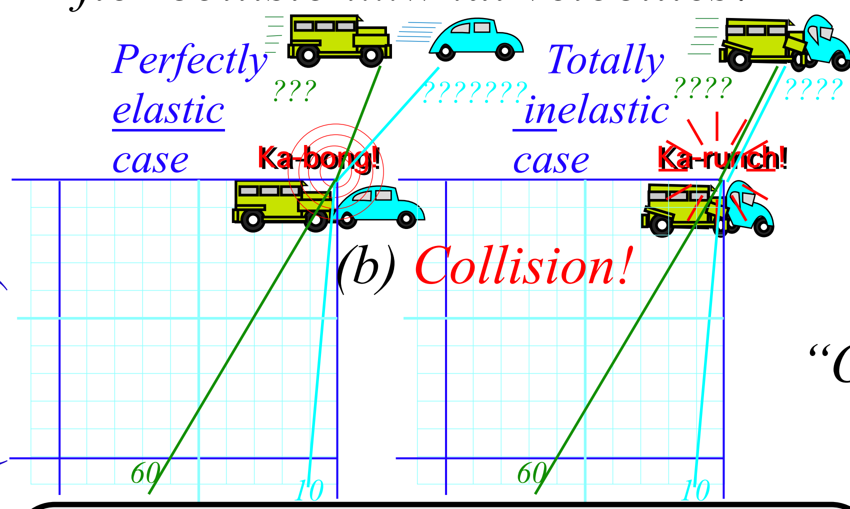

Conventional solution: Look up the usual *momentum* and *energy* formulas/axioms:
$\Sigma_i m V_i(\text{initial}) = \Sigma_i m V_i(\text{final})$
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and solve...

Inventor of
"*Occam's Razor*"

William of Ockham
1285-1349

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V_{SUV} and V_{VW} change violently
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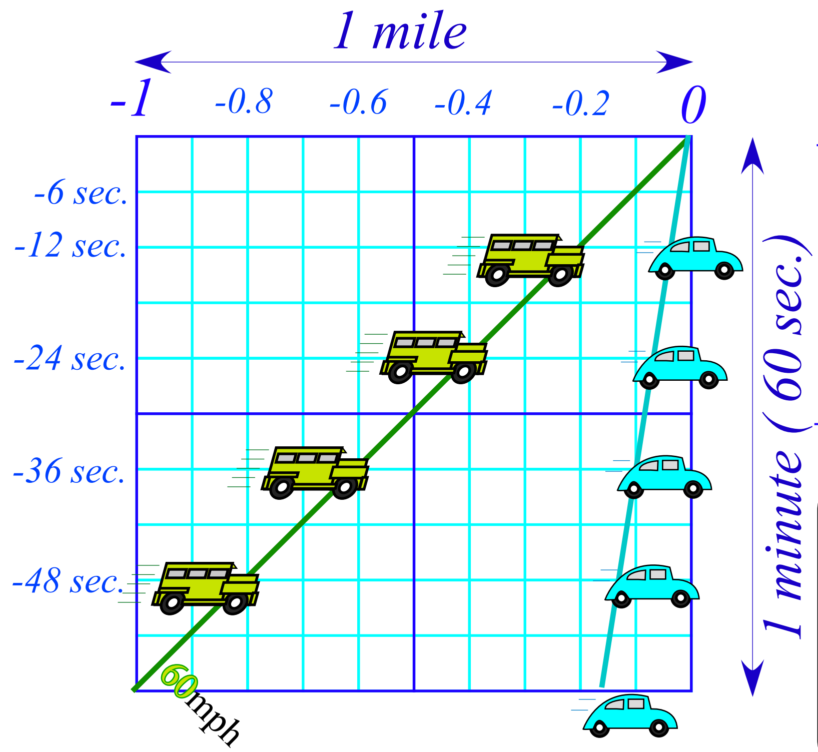
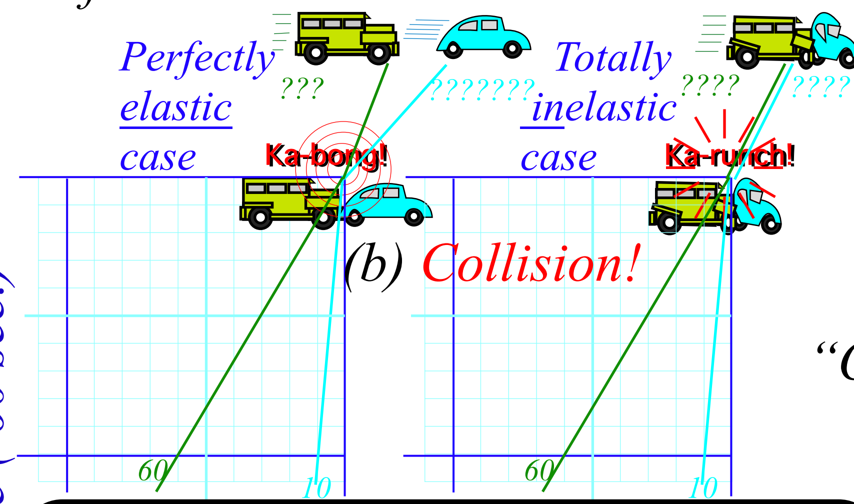
$P_{Total} = M_{SUV} V_{SUV} + M_{VW} V_{VW}$

A problem in ***space-time*** : (60mph Cell-faxing 4ton SUV rear-ends 10mph 1ton VW)

Before collision.....



After collision...what velocities?



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"*Pluralitas non set poneda sine necessitate.*"
and has a number of interpretations:
1. Literally:"*Don't make pluralities of conjectures without necessity.*"
2. Logically: "*Assume less to prove more.*"
3. Practical coding advice: "*Keep it simple, make it powerful.*"

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A problem in *space-time* : (60mph Cell-faxing 4ton SUV rear-ends 10mph 1ton VW)

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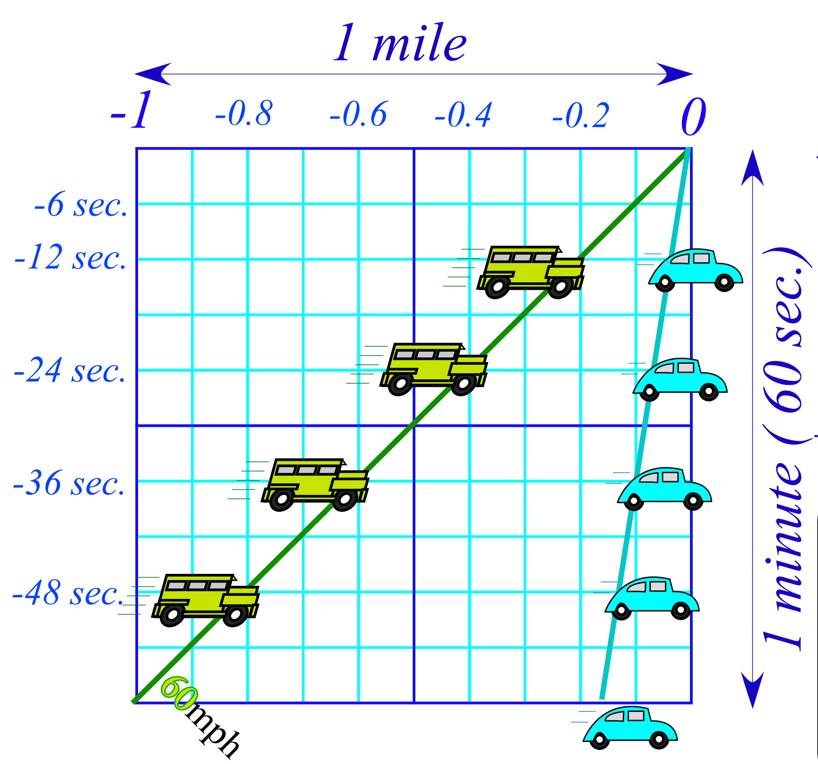
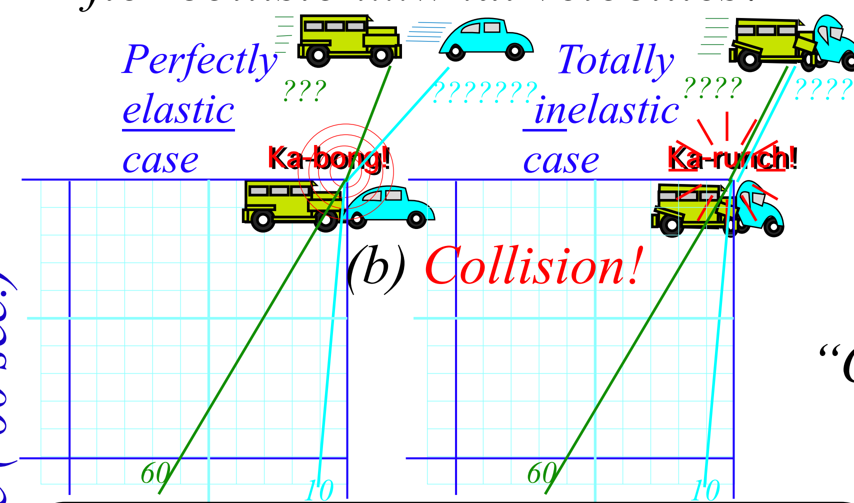
$P_{Total} = M_{SUV} V_{SUV} + M_{VW} V_{VW}$

Before collision..... *After collision...what velocities?*





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GO! (INITIAL or IN) *STOP! (FINAL or FIN)*

$$M_{SUV}V^{IN}_{SUV} + M_{VW}V^{IN}_{VW} = M_{SUV}V^{FIN}_{SUV} + M_{VW}V^{FIN}_{VW} = constant$$

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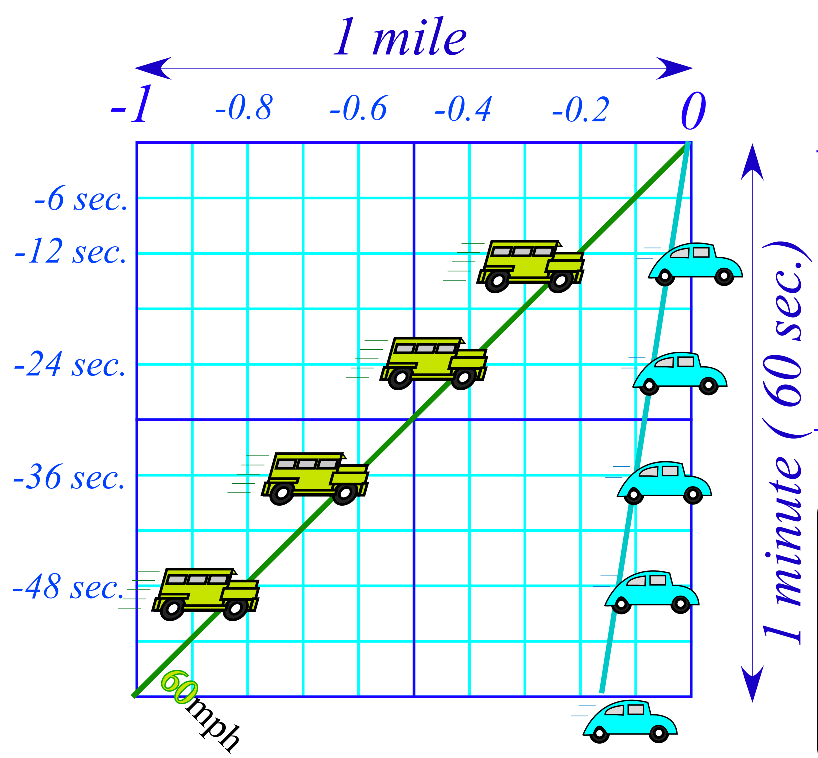
Before collision.....



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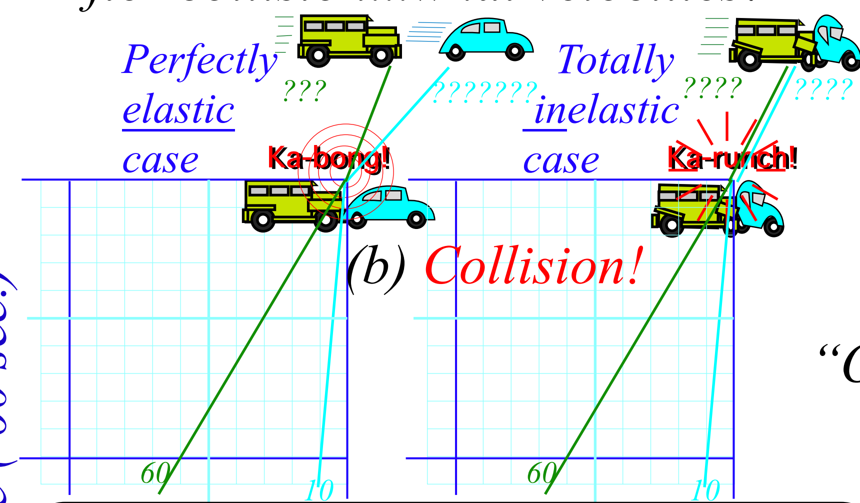

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$$4 \cdot 60 + 1 \cdot 10 = 4 \cdot ? + 1 \cdot ?? = 250$$

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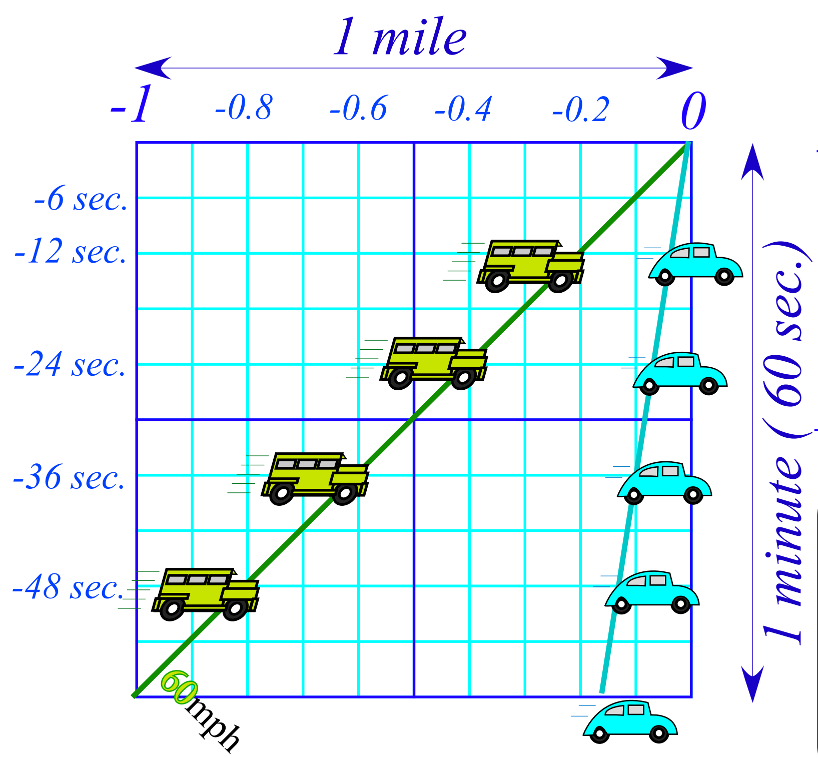

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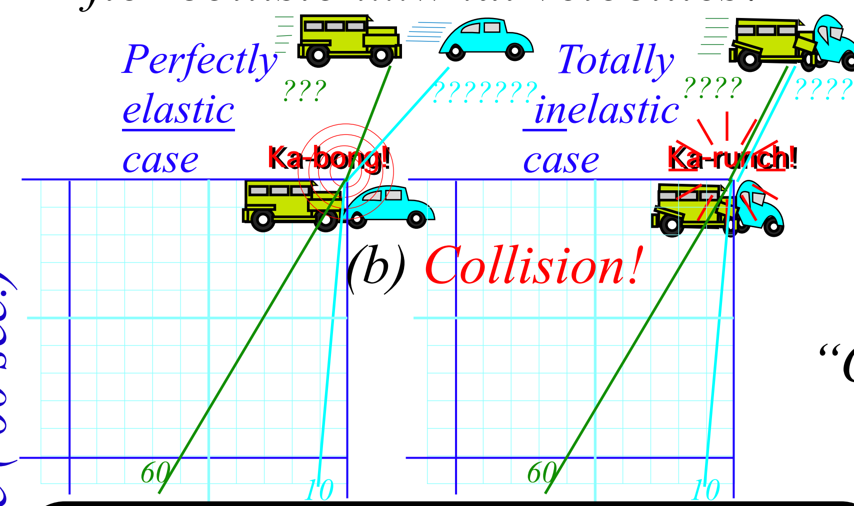

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$$4 \cdot 60 + 1 \cdot 10 = 4 \cdot ? + 1 \cdot ?? = 250$$

It's a simple *Cartesian* equation

$$4 \cdot x + 1 \cdot y = 250$$

Rene Descartes
1596-1650

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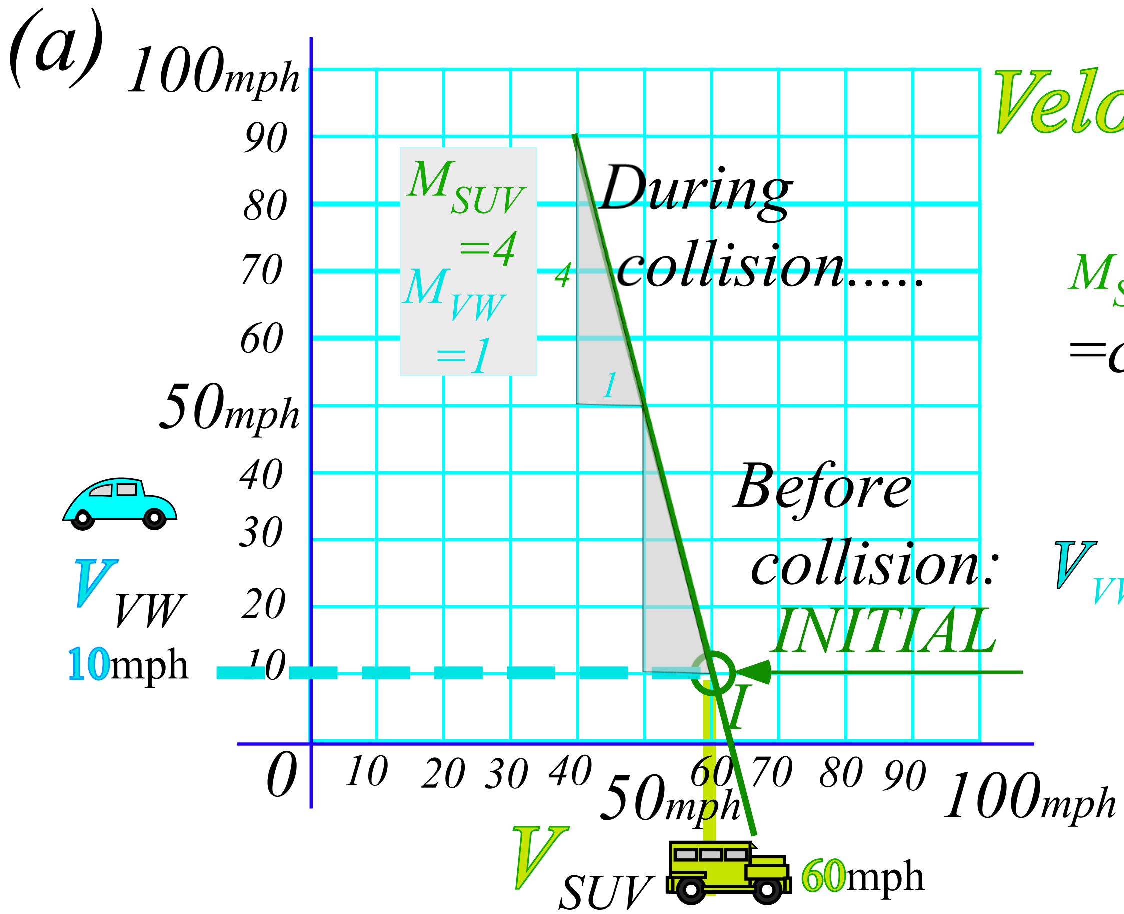


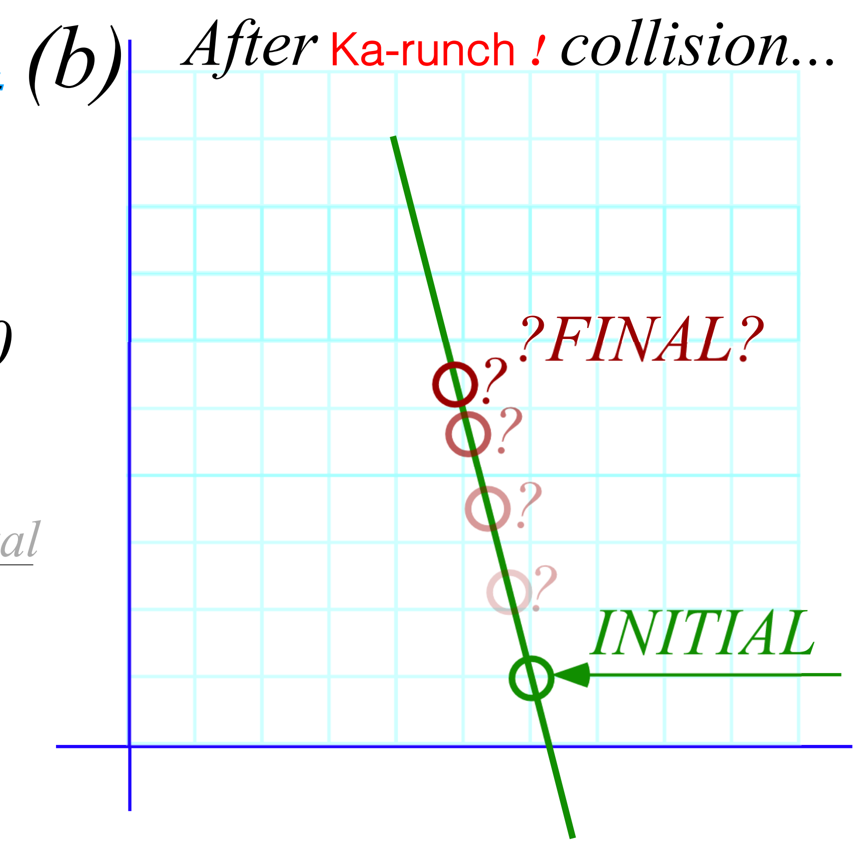
Velocity-velocity plot of Axiom-1:

$M_{SUV}V_{SUV} + M_{VW}V_{VW}$

$= constant = P_{Total} = 250$

$V_{VW} = -\frac{M_{SUV}}{M_{VW}} V_{SUV} + \frac{P_{Total}}{M_{VW}}$

$= -\ 4\ V_{SUV} + 250$



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...with a simple *Cartesian* line-plot.

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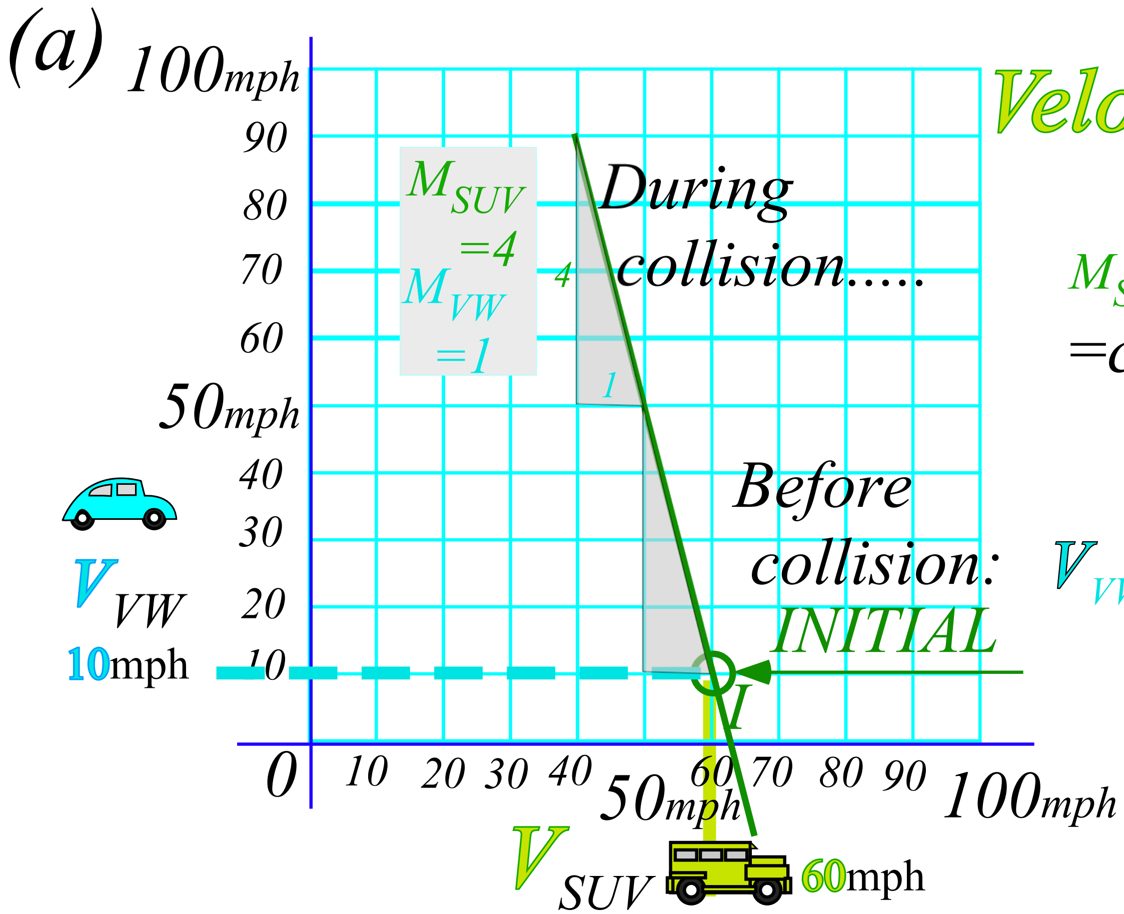
Geometry of momentum conservation axiom

→ *Totally Inelastic "ka-runch" collisions*

Perfectly Elastic "ka-bong" and Center Of Momentum (COM) symmetry

+Intro to weighted-averages and vector notation

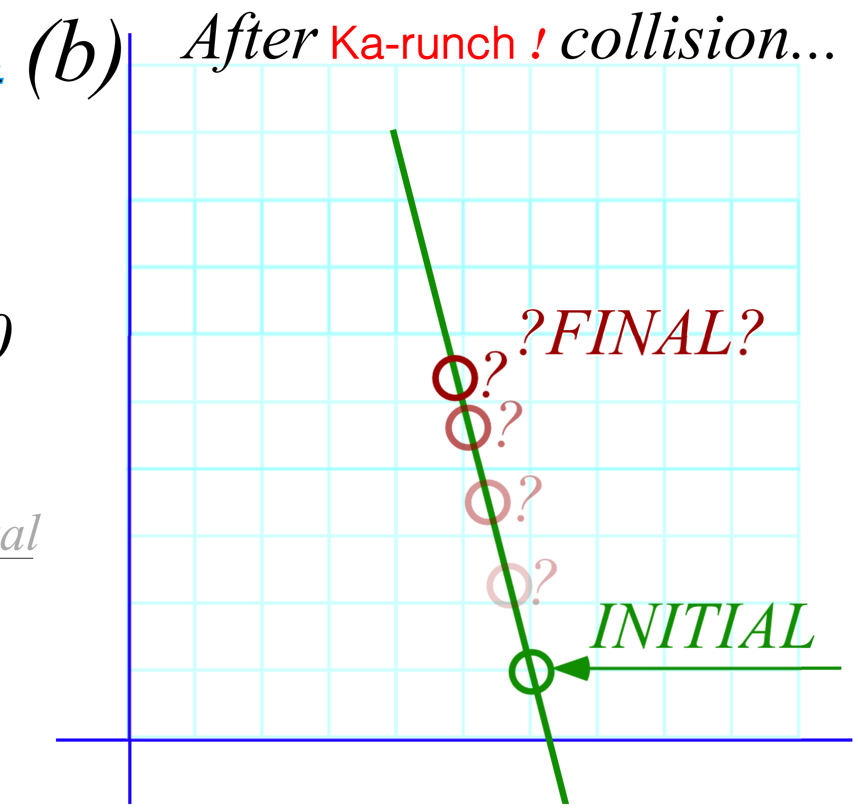
Comments on idealization in classical models



Velocity-velocity plot of Axiom-1:

$$M_{SUV} V_{SUV} + M_{VW} V_{VW}$$
$$= constant = P_{Total} = 250$$

$$V_{VW} = -\frac{M_{SUV}}{M_{VW}} V_{SUV} + \frac{P_{Total}}{M_{VW}}$$
$$= -4 \, V_{SUV} + 250$$

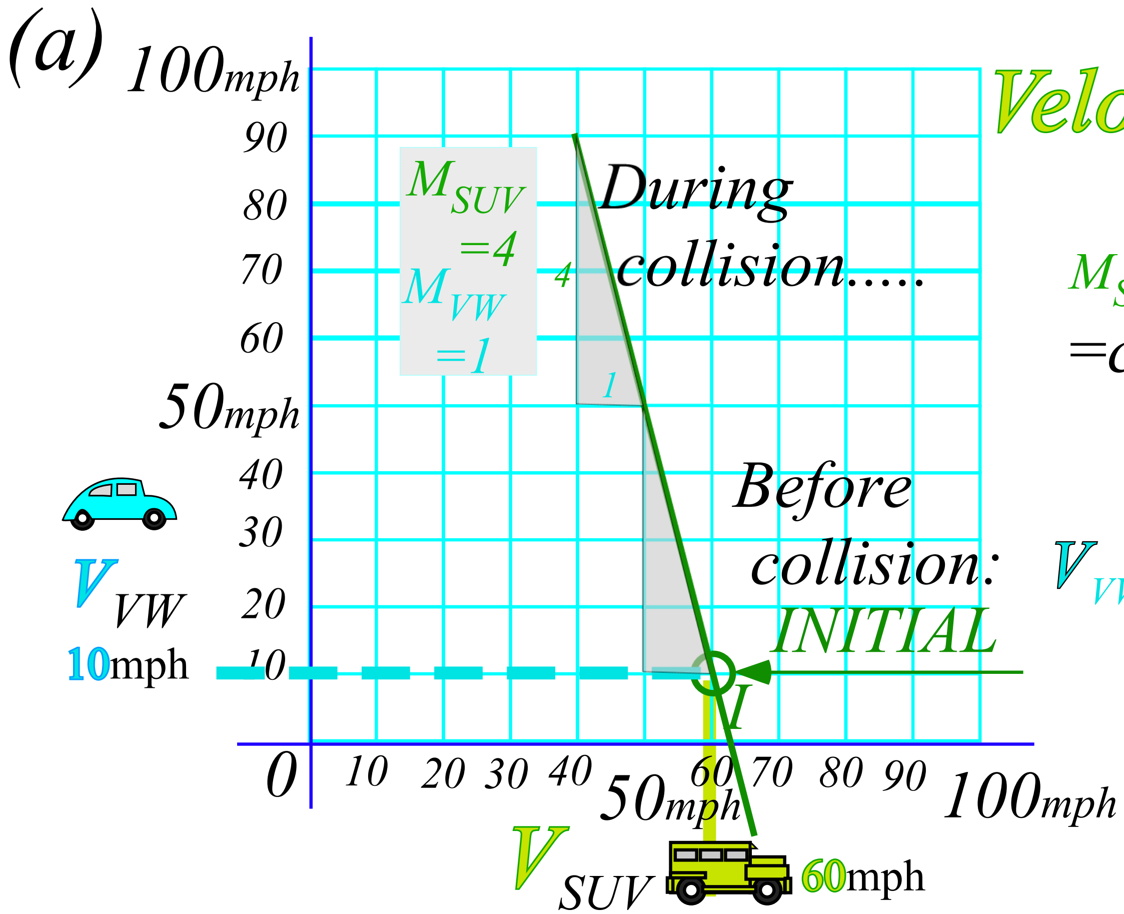


It's a simple *Cartesian* equation...

$$4 \cdot x + 1 \cdot y = 250$$
$$y = 250 - 4 \cdot x$$

...with a simple *Cartesian* line-plot.

Rene Descartes
1596-1650

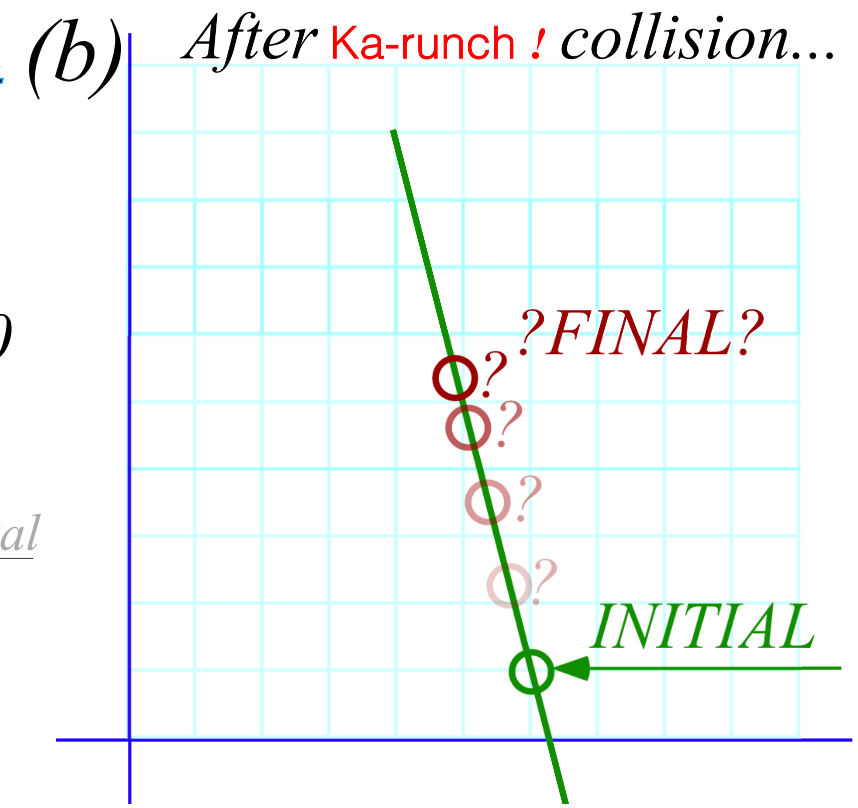


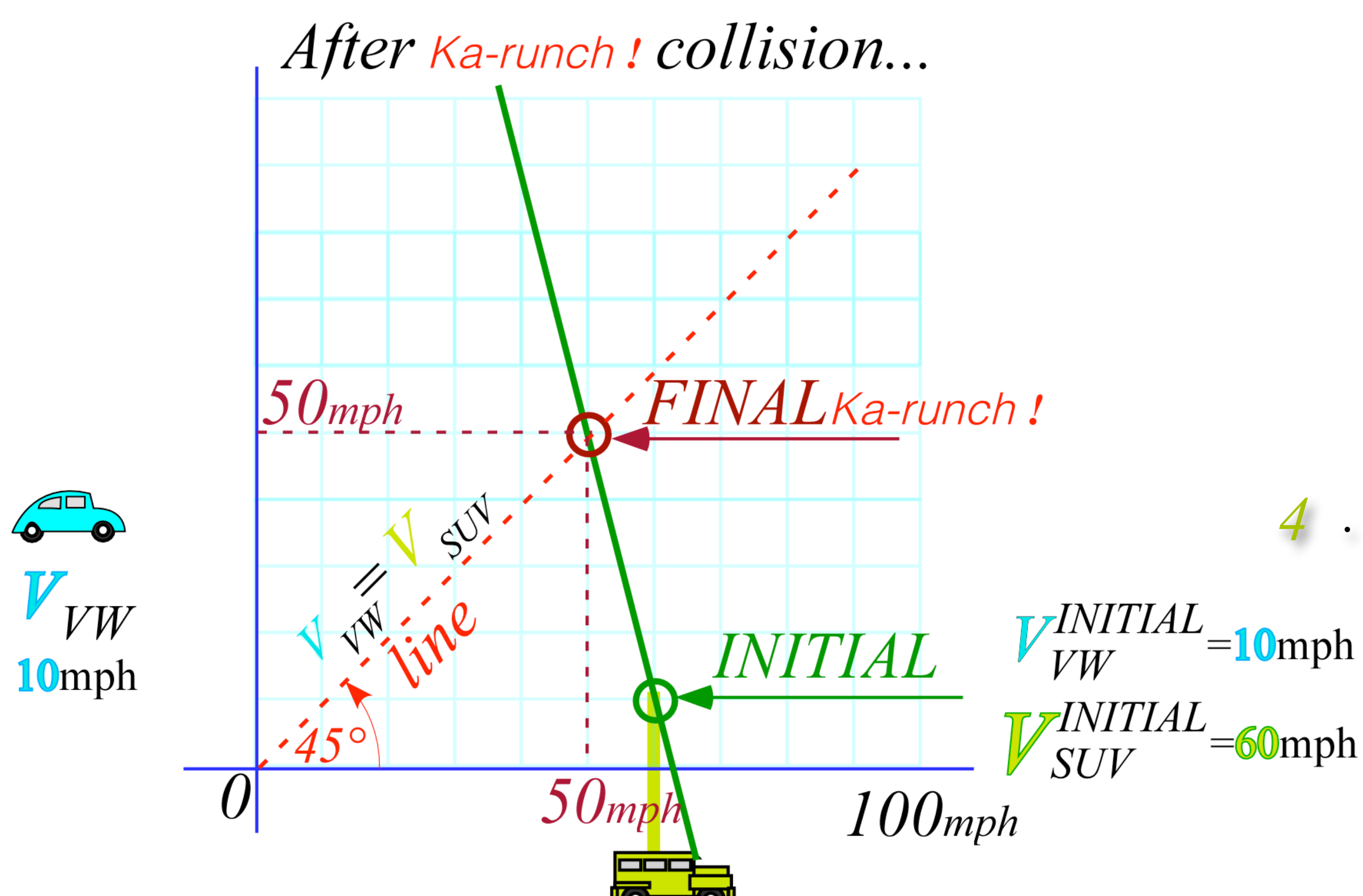
Velocity-velocity plot of Axiom-1:

$$M_{SUV}V_{SUV} + M_{VW}V_{VW} = constant = P_{Total} = 250$$

$$V_{VW} = -\frac{M_{SUV}}{M_{VW}}V_{SUV} + \frac{P_{Total}}{M_{VW}}$$

$$= -\ 4\ V_{SUV} + 250$$





It's a simple *Cartesian* equation...

$$4\cdot x + 1\cdot y = 250$$

$$y = 250 - 4\cdot x$$

$$5\cdot x = 250 \quad \text{...with } y = x = 50$$

...with a simple *Cartesian* line-plot.

Rene Descartes
1596-1650

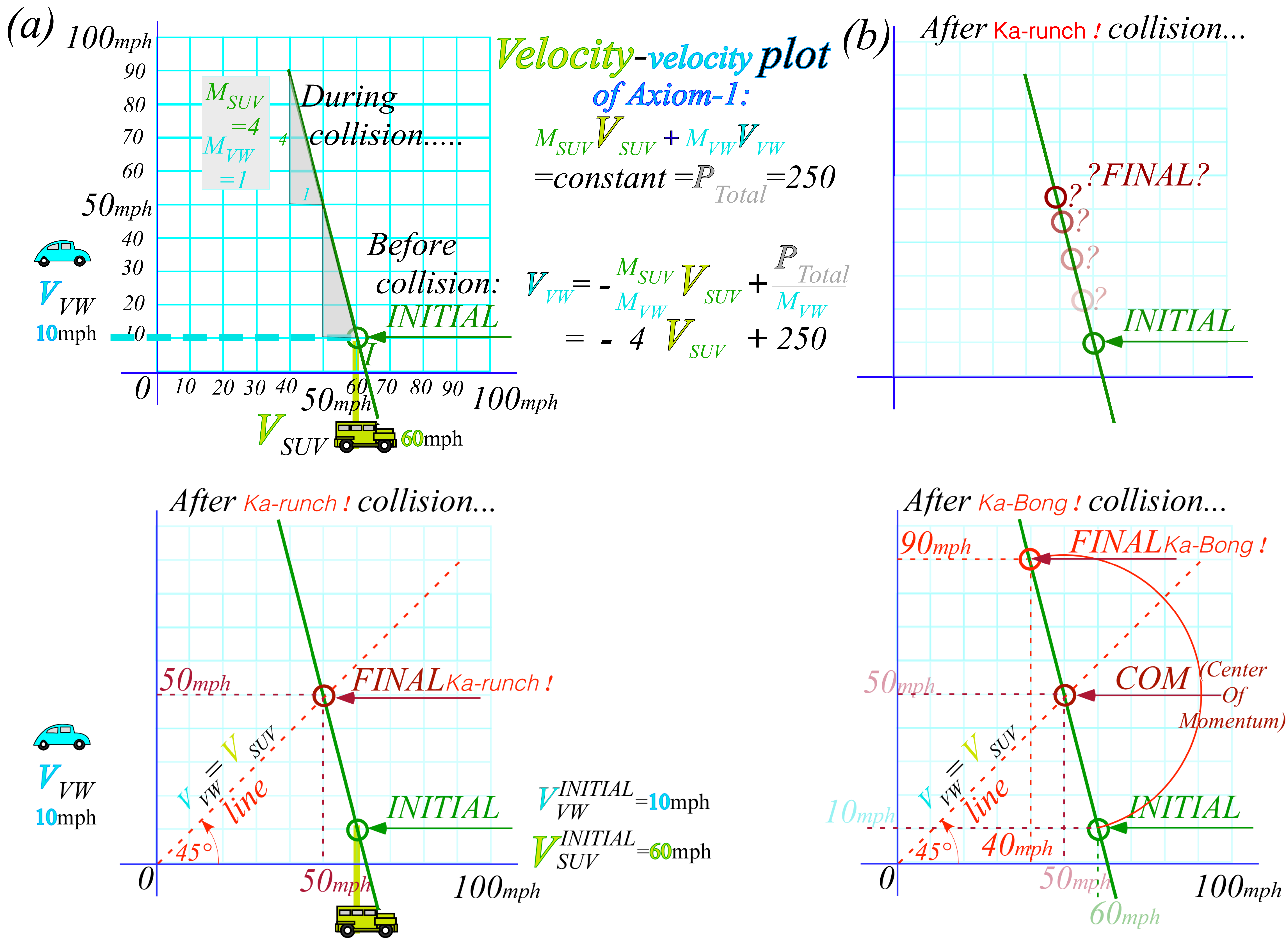
Geometry of momentum conservation axiom

Totally Inelastic "ka-runch" collisions

Perfectly Elastic "ka-bong" and Center Of Momentum (COM) symmetry

+Intro to weighted-averages and vector notation

Comments on idealization in classical models


(a)
Velocity-velocity plot of Axiom-1:
$M_{SUV}V_{SUV} + M_{VW}V_{VW}$
$=constant = P_{Total} = 250$
$M_{SUV} = 4$
$M_{VW} = 1$
During collision.....
Before collision:
INITIAL
$V_{VW} = -\frac{M_{SUV}}{M_{VW}}V_{SUV} + \frac{P_{Total}}{M_{VW}}$
$= - 4 V_{SUV} + 250$
100mph
90
80
70
60
50mph
40
30
20
10
0
10 20 30 40 50mph 60 70 80 90 100mph
V_{VW}
10mph
V_{SUV}
60mph
(b)
After Ka-runch ! collision...
?FINAL?
INITIAL
After Ka-runch ! collision...
50mph
FINAL Ka-runch !
INITIAL
$V_{VW} = V_{SUV}$ line
45°
50mph
100mph
$V_{VW}^{INITIAL}$ =10mph
$V_{SUV}^{INITIAL}$ =60mph
After Ka-Bong ! collision...
90mph
FINAL Ka-Bong !
50mph
COM
(Center Of Momentum)
10mph
40mph
INITIAL
50mph
60mph
100mph

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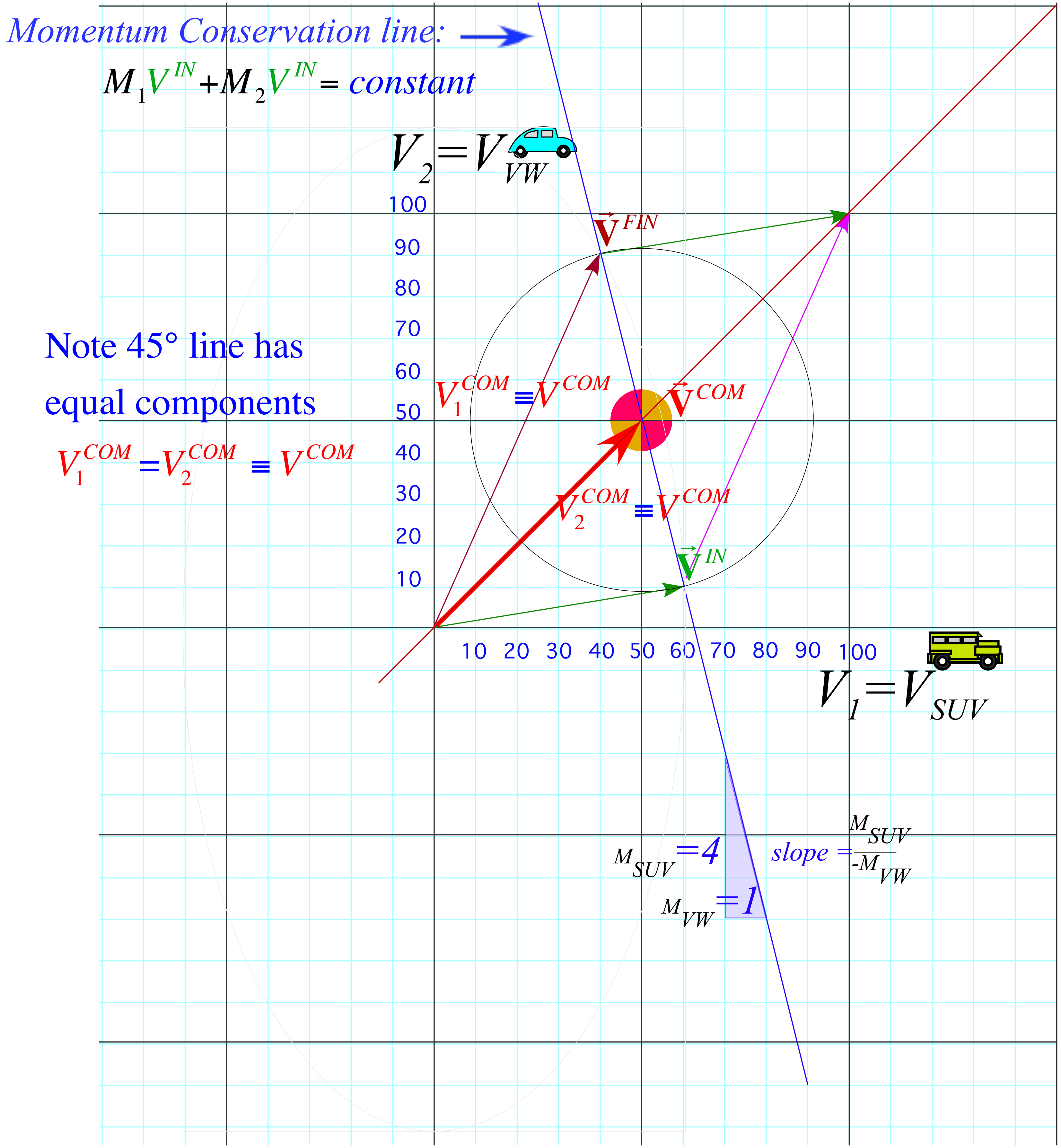
Geometry of Momentum Conservation **Axiom - 1**

$$(M_1+M_2)V^{COM} = M_1V_1^{IN}+M_2V_2^{IN} = M_1V_1^{COM}+M_2V_2^{COM} = M_1V_1^{FIN}+M_2V_2^{FIN} = M_{Total}V^{COM}$$



Geometry of Momentum Conservation **Axiom-1**

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Momentum Conservation line: →

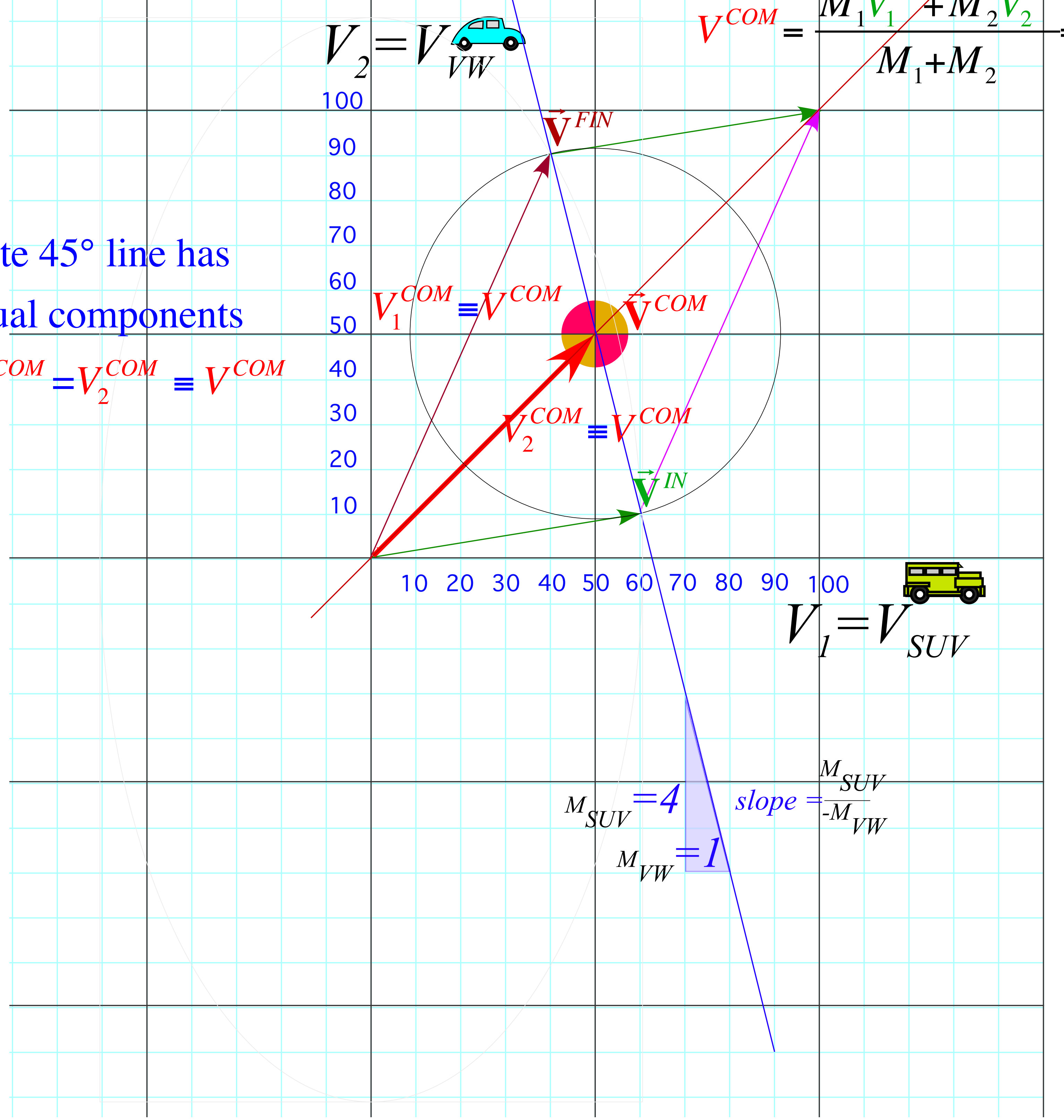
$$M_1V^{IN}+M_2V^{IN} = \textit{constant}$$

Divide **Axiom-1** by $M_{Total} = (M_1+M_2)$

$$V^{COM} = \frac{M_1V_1^{IN}+M_2V_2^{IN}}{M_1+M_2} = \frac{M_1V_1^{COM}+M_2V_2^{COM}}{M_1+M_2} = \frac{M_1V_1^{FIN}+M_2V_2^{FIN}}{M_1+M_2} = 50$$

Note 45° line has equal components

$$V_1^{COM} = V_2^{COM} \equiv V^{COM}$$



Geometry of Momentum Conservation **Axiom - 1**

$$(M_1+M_2)V^{COM} = M_1V_1^{IN}+M_2V_2^{IN} = M_1V_1^{COM}+M_2V_2^{COM} = M_1V_1^{FIN}+M_2V_2^{FIN} = M_{Total}V^{COM}$$

Momentum Conservation line: →

$$M_1V^{IN}+M_2V^{IN} = constant$$

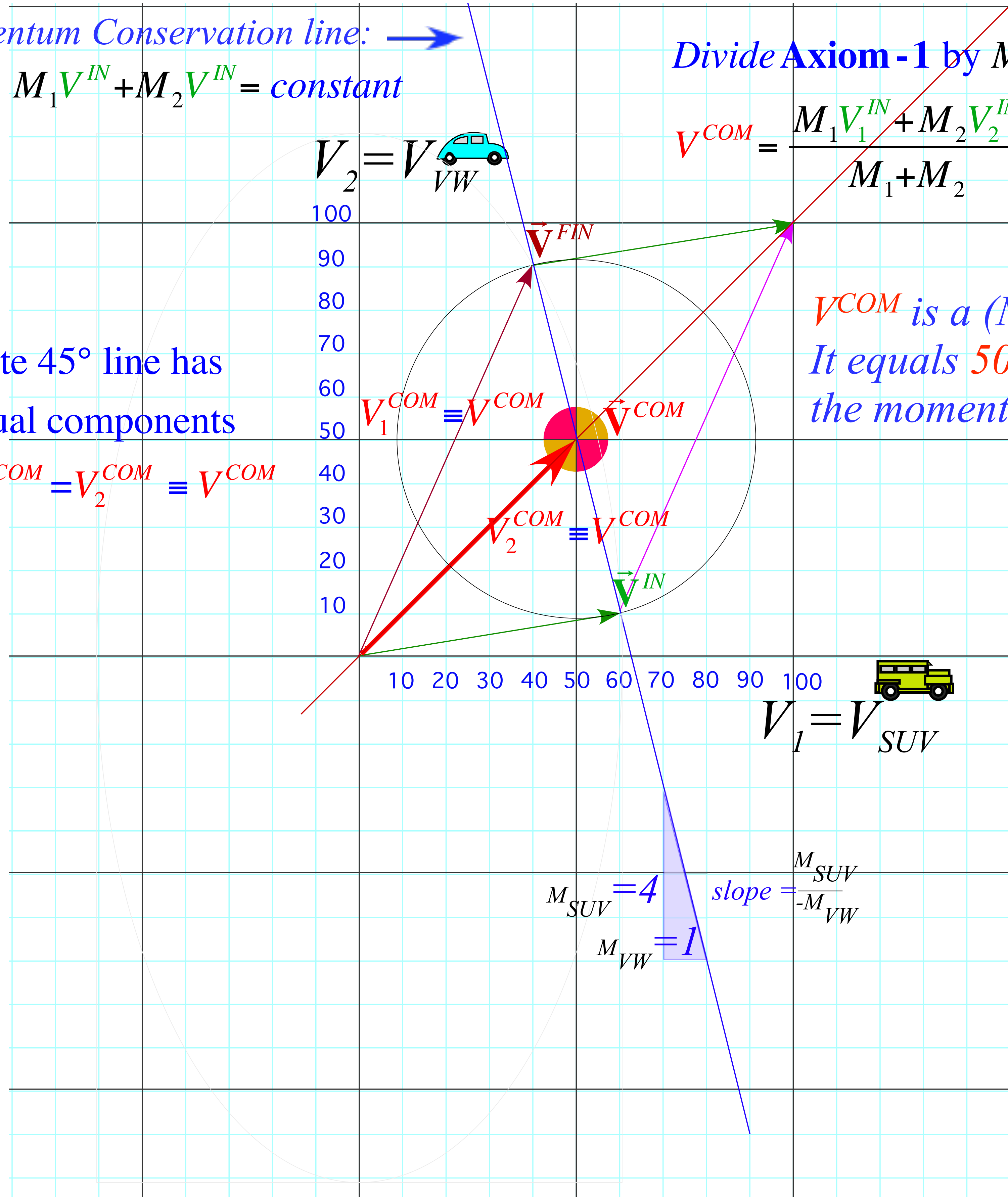
Divide **Axiom - 1** by $M_{Total} = (M_1+M_2)$

$$V^{COM} = \frac{M_1V_1^{IN}+M_2V_2^{IN}}{M_1+M_2} = \frac{M_1V_1^{COM}+M_2V_2^{COM}}{M_1+M_2} = \frac{M_1V_1^{FIN}+M_2V_2^{FIN}}{M_1+M_2} = 50$$

V^{COM} *is a* (M_1,M_2) ***Weighted Average*** *of* V_1 *and* V_2
It equals 50 for every point (V_1,V_2) *on the momentum line*

Note 45° line has equal components

$$V_1^{COM} = V_2^{COM} \equiv V^{COM}$$



Geometry of momentum conservation axiom

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+Intro to weighty averages and vector notation

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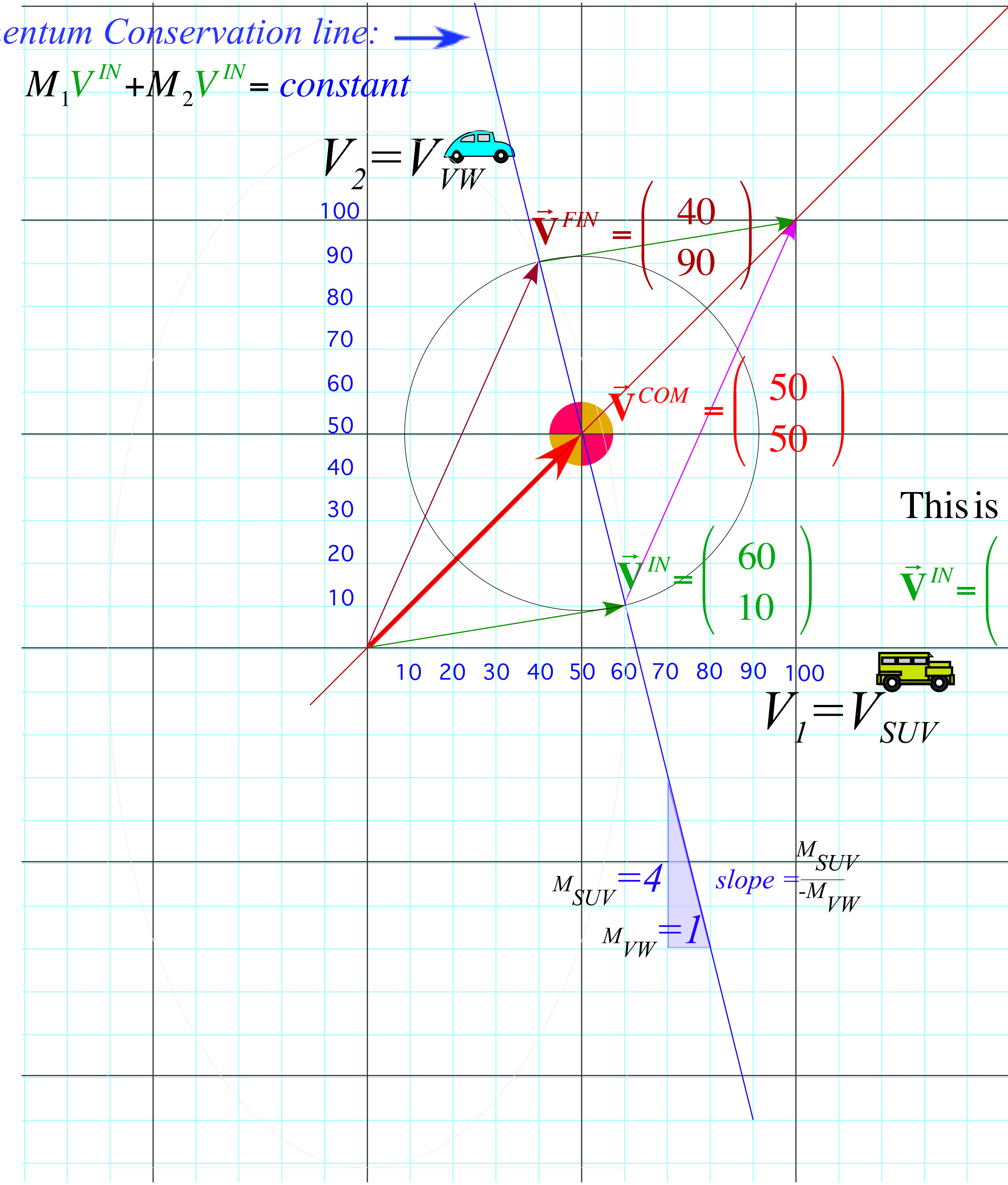
Geometry of Momentum Conservation **Axiom - 1**

$$(M_1+M_2)V^{COM} = M_1V_1^{IN} + M_2V_2^{IN} = M_1V_1^{FIN} + M_2V_2^{FIN}$$

Momentum Conservation line: →

$$M_1V^{IN} + M_2V^{IN} = constant$$

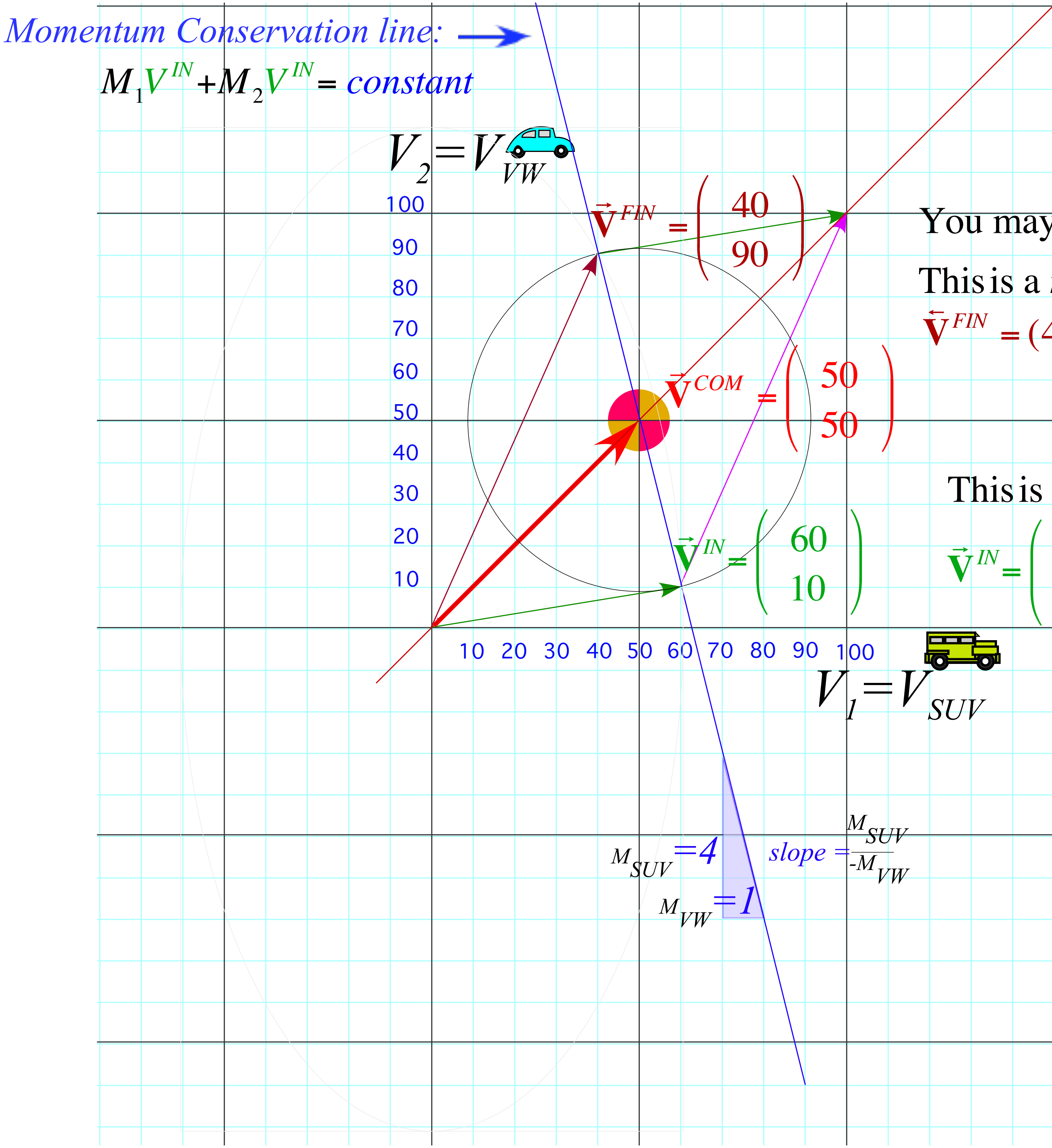


This is a *column-vector* (or *ket* $|IN\rangle$ in QM)

$$\vec{V}^{IN} = \begin{pmatrix} 60 \\ 10 \end{pmatrix}$$

Geometry of Momentum Conservation **Axiom - 1**

$$(M_1+M_2)V^{COM} = M_1 V_1^{IN} + M_2 V_2^{IN} = M_1 V_1^{FIN} + M_2 V_2^{FIN}$$



You may be used to giving coordinates as (x,y).

This is a *row-vector* (or *bra* $\langle FIN|$ in QM)

$\vec{\mathbf{V}}^{FIN} = (40,90)$

This is a *column-vector* (or *ket* $|IN\rangle$ in QM)

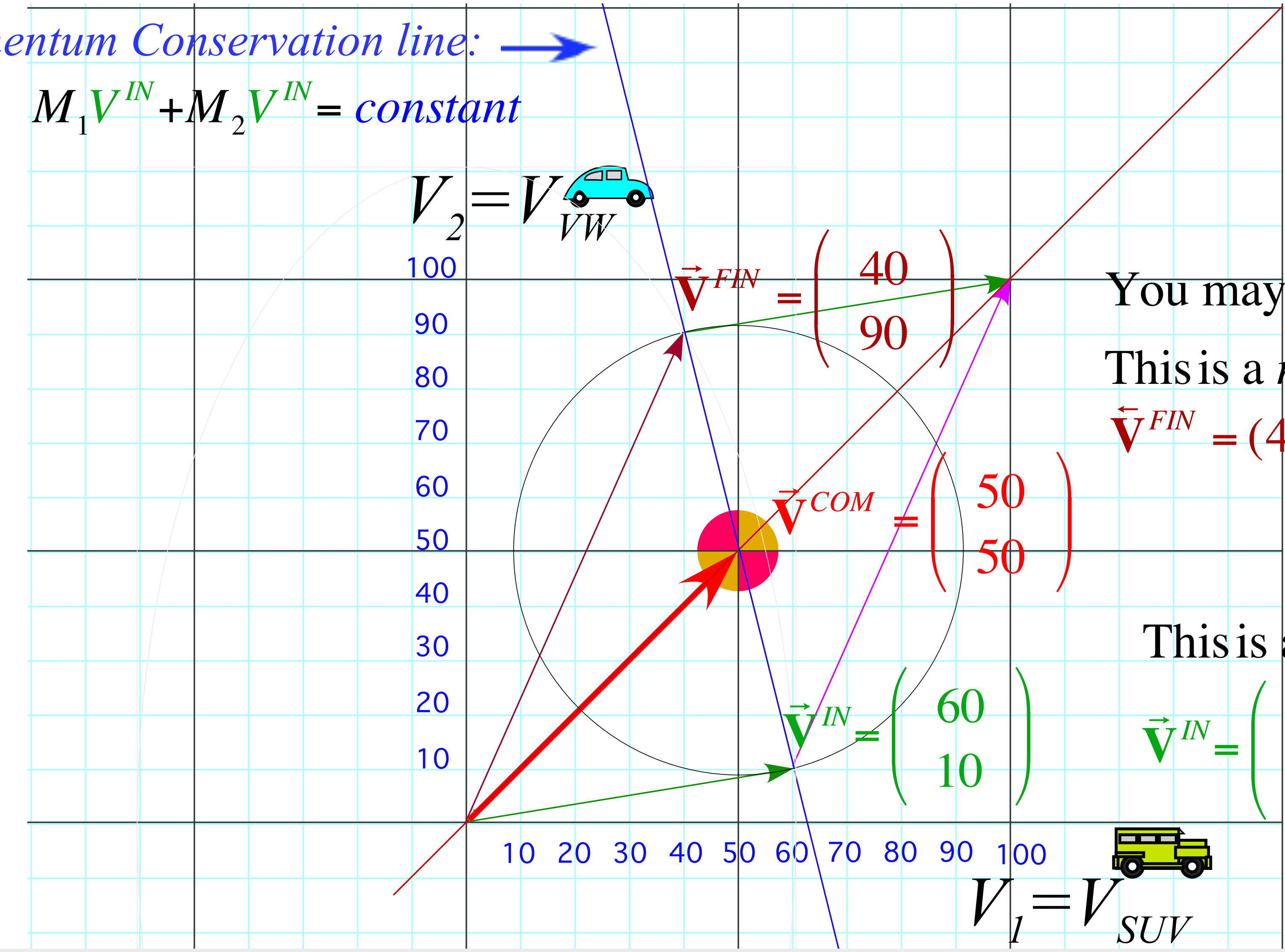
$$\vec{\mathbf{V}}^{IN} = \begin{pmatrix} 60 \\ 10 \end{pmatrix}$$

Geometry of Momentum Conservation **Axiom - 1**

$$(M_1+M_2)V^{COM}=M_1V_1^{IN}+M_2V_2^{IN}=M_1V_1^{FIN}+M_2V_2^{FIN}$$

Momentum Conservation line: →

$$M_1V^{IN}+M_2V^{IN}=constant$$



You may be used to giving coordinates as (x,y).

This is a *row-vector* (or *bra* $\langle FIN|$ in QM)

$$\vec{\mathbf{V}}^{FIN}=(40,90)$$

This is a *column-vector* (or *ket* $|IN\rangle$ in QM)

$$\vec{\mathbf{V}}^{IN}=\begin{pmatrix}60\\10\end{pmatrix}$$

This is a *dot* product (or *scalar* product)

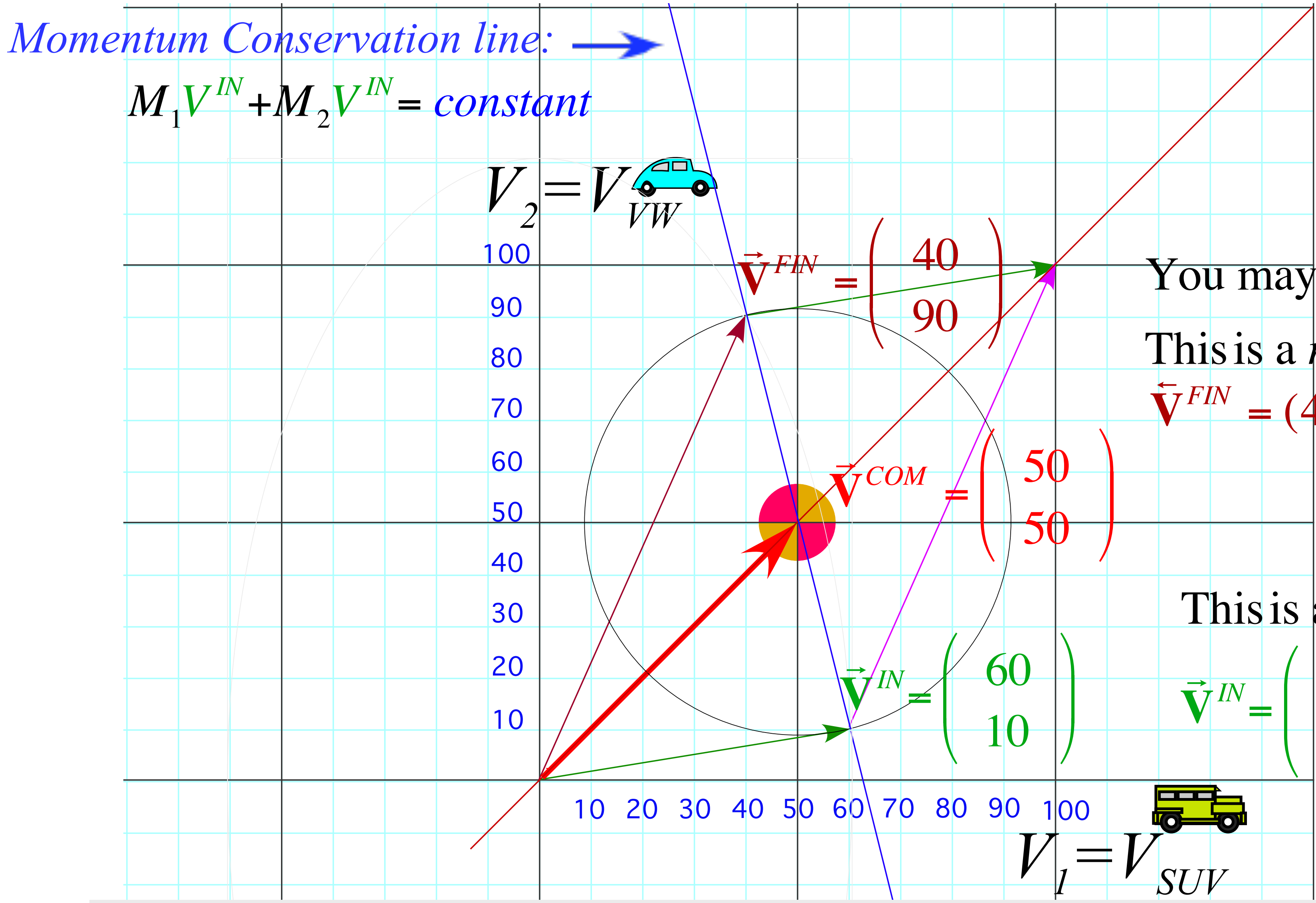
$$\overleftarrow{\mathbf{V}}^{FIN}\bullet\vec{\mathbf{V}}^{IN}=(40,90)\bullet\begin{pmatrix}60\\10\end{pmatrix}=\langle FIN|IN\rangle=\ 40\ 60\ +\ 90\ 10=\ 2400+900=3300$$

of a *row-vector* $\overleftarrow{\mathbf{V}}^{FIN}=(40,90)$ (or *bra* $\langle FIN|$)

with *column-vector* $=\begin{pmatrix}60\\10\end{pmatrix}$ (or *ket* $|IN\rangle$)

Geometry of Momentum Conservation **Axiom - 1**

$$(M_1+M_2)V^{COM} = M_1 V_1^{IN} + M_2 V_2^{IN} = M_1 V_1^{FIN} + M_2 V_2^{FIN}$$



You may be used to giving coordinates as (x,y).

This is a *row-vector* (or *bra* $\langle FIN|$ in QM)

$\vec{V}^{FIN} = (40,90)$

This is a *column-vector* (or *ket* $|IN\rangle$ in QM)

$$\vec{V}^{IN} = \begin{pmatrix} 60 \\ 10 \end{pmatrix}$$

This is a *outer* product (or *tensor* product)

$$\vec{V}^{IN} \otimes \vec{V}^{FIN} = \begin{pmatrix} 60 \\ 10 \end{pmatrix} \otimes (40,90) = |IN\rangle\langle FIN| = \begin{pmatrix} 60\ 40 & 60\ 90 \\ 10\ 40 & 10\ 90 \end{pmatrix} = \begin{pmatrix} 2400 & 5400 \\ 400 & 900 \end{pmatrix}$$

of a *column-vector* $= \begin{pmatrix} 60 \\ 10 \end{pmatrix}$ (or *ket* $|IN\rangle$)

with a *row-vector* $\vec{V}^{FIN} = (40,90)$ (or *bra* $\langle FIN|$)

Geometry of momentum conservation axiom

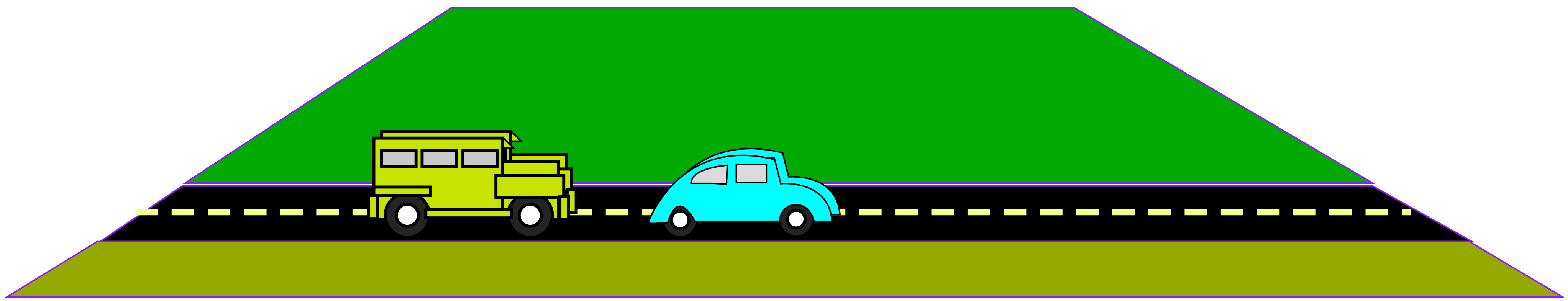
Totally Inelastic "ka-runch"collisions

Perfectly Elastic "ka-bong" and Center Of Momentum (COM) symmetry

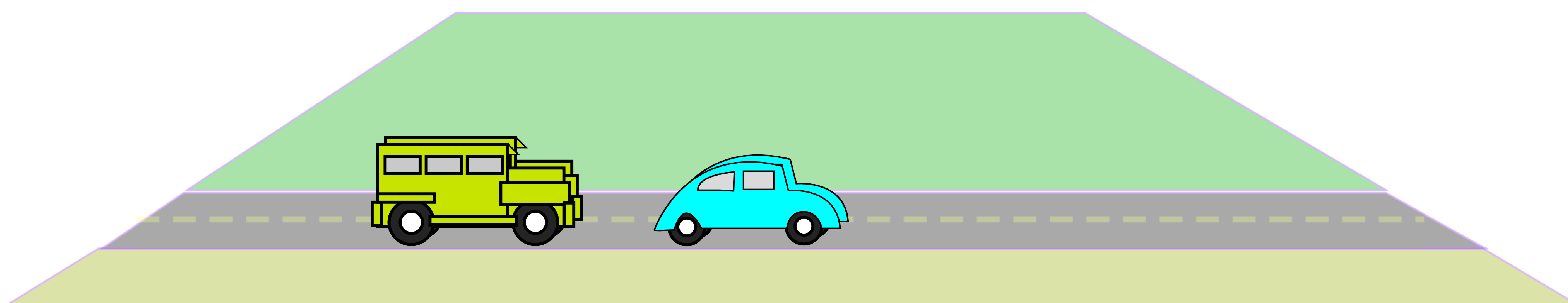
+Intro to weighty-averages and vector notation

Comments on idealization in classical models

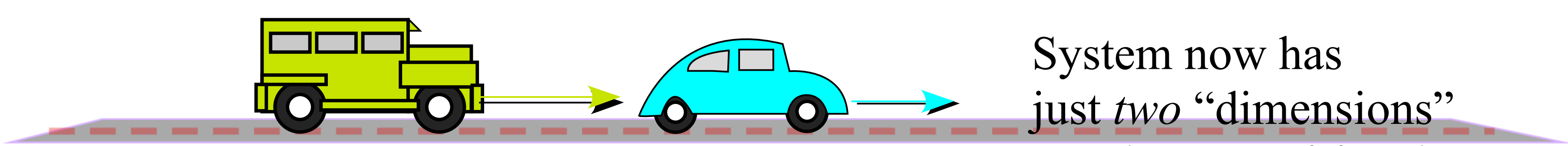
The SUV and VW *Idealized* thought experiments



Idealization 1. Ignore background.
(No rolling friction, air resistance, etc.)



Idealization 2. Make each 1-dimensional.
(Cars "constrained" to ride on frictionless rail)

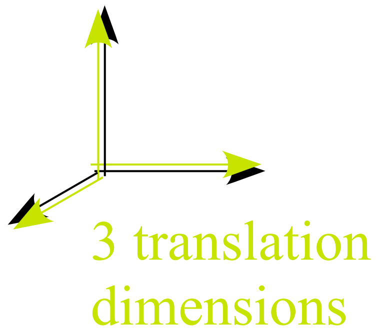


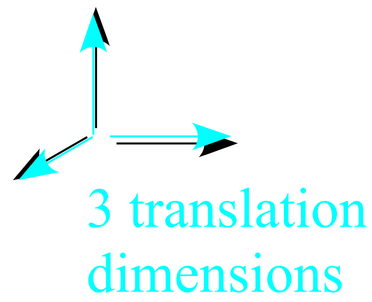
System now has
just *two* "dimensions"
or "*degrees-of-freedom*"

Landscape 1.1 Idealized model for collision model and thought experiments

Summary of Classical Mechanical Degrees of Freedom

Translation (Each body has 3 translational degrees of freedom) (Intoduced in Units 1 and 2)

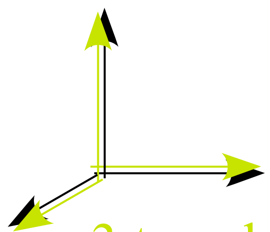




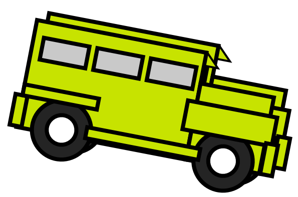
6 translational degrees of freedom for SUV and VW.

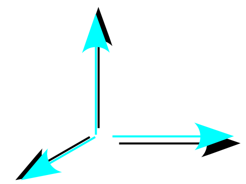
Summary of Classical Mechanical Degrees of Freedom

Translation (Each body has 3 translational degrees of freedom) (Intoduced in Units 1 and 2)

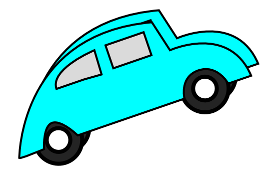


3 translation dimensions



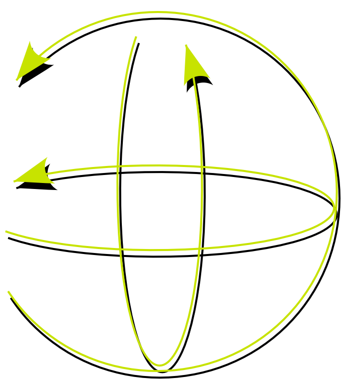


3 translation dimensions



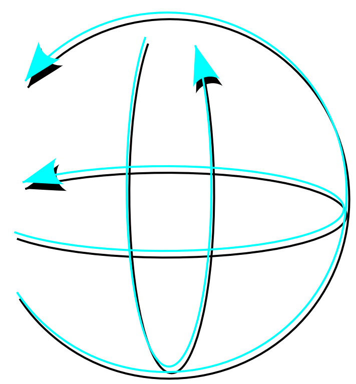
6 translational degrees of freedom for SUV and VW.

Rotation (Each body has 3 rotationaldegrees of freedom) (Intoduced in Units 3 and 7)



3 rotational dimensions

yaw-pitch-roll Euler angles



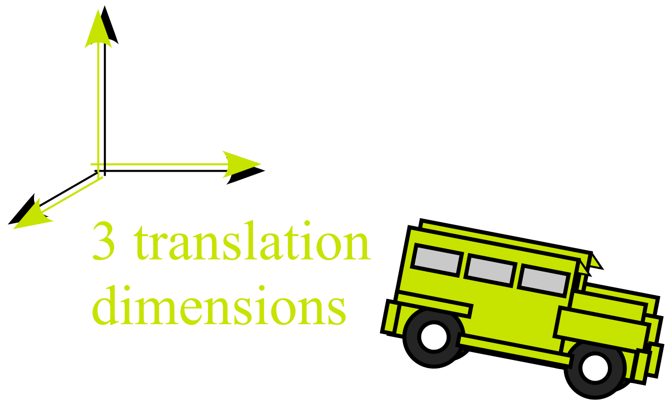
3 rotational dimensions

yaw-pitch-roll Euler angles

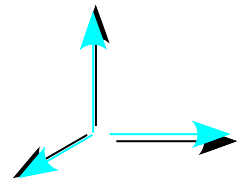
6 rotational degrees of freedom for SUV and VW.

Summary of Classical Mechanical Degrees of Freedom

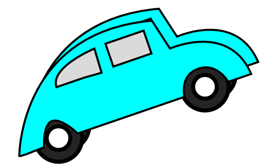
Translation (Each body has 3 translational degrees of freedom) (Intoduced in Units 1 and 2)



3 translation dimensions



3 translation dimensions



6 translational degrees of freedom for SUV and VW.

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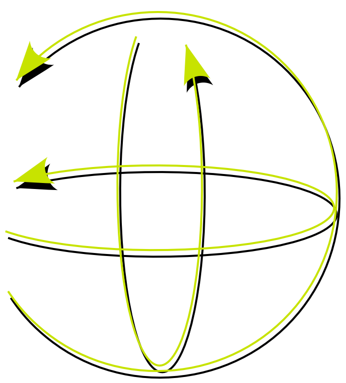
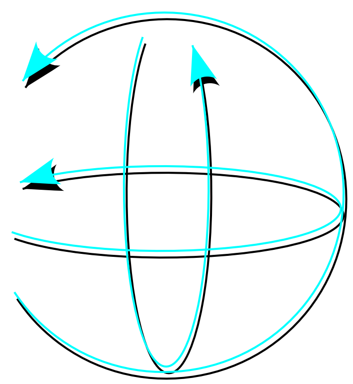


3 rotational dimensions

yaw-pitch-roll Euler angles



3 rotational dimensions

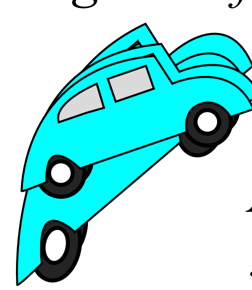
yaw-pitch-roll Euler angles

6 rotational degrees of freedom for SUV and VW.

SUV and VW system involves
12 rigid-body degrees of freedom

Vibration (Each body has <u>many</u> vibrational degrees of freedom) (Intoduced in Units 3-8)

Generalized Curvilinear Coordinates (GCC) introduced in Unit 1 Chapters 10 -12



An N-atom molecule has 3N-6 vibrational degrees of freedom

Landscape 1.2 Some idealized classical model degrees of freedom

Geometry of Galilean translation symmetry

45° shift in (V_1,V_2)-space
Time reversal symmetry
...of COM collisions

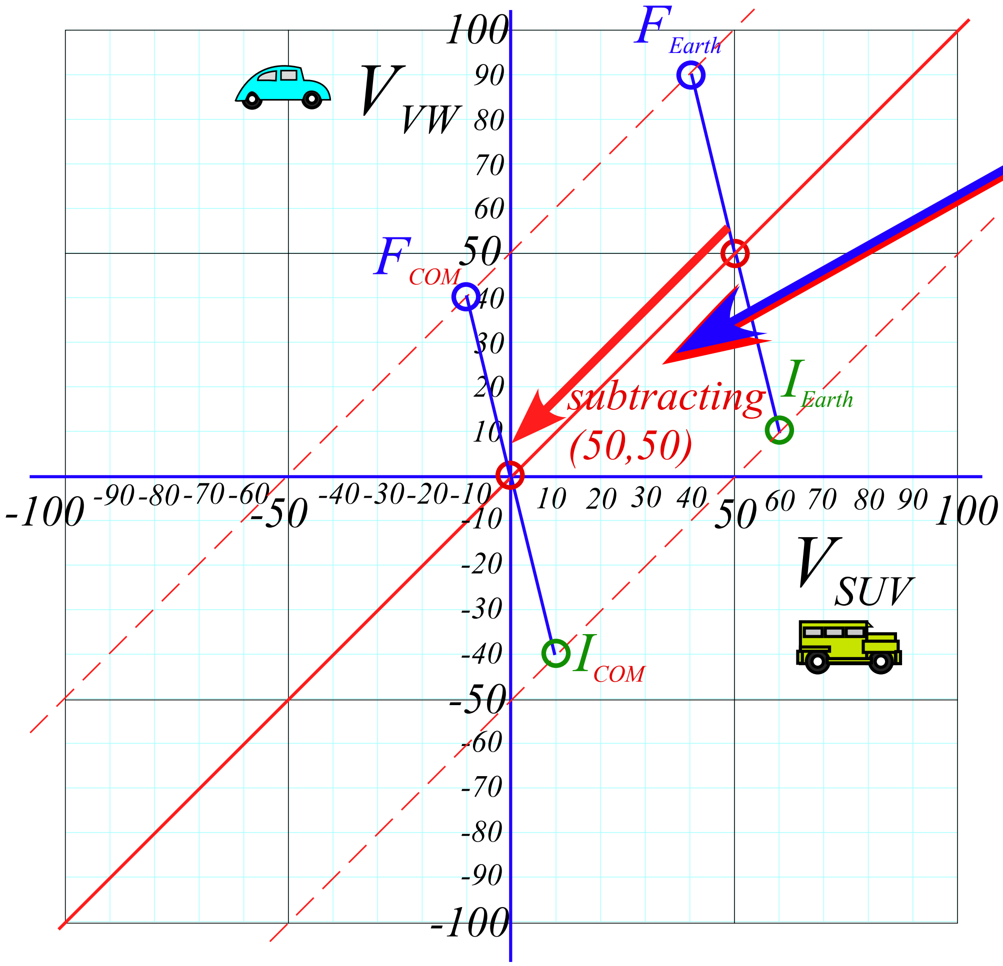
A problem in *space-time* : (60mph Cell-faxing 4ton SUV rear-ends 10mph 1ton VW)

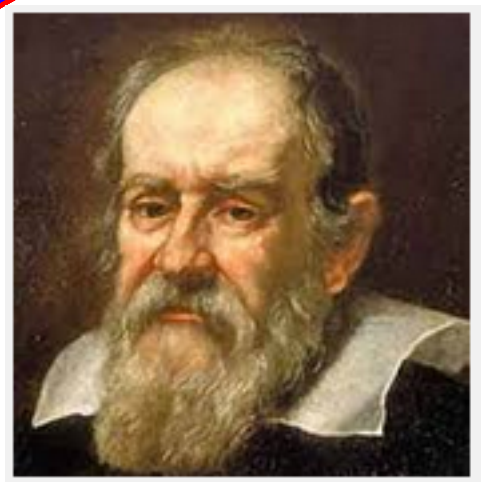
Geometry of Galilean translation (A symmetry transformation)

If you increase your velocity by 50 mph,... *(In some direction x,y, or z...)*

...the rest of the world appears to be 50 mph slower *(In that direction...)*

(a) Galileo transforms to COM frame





Galileo Galilei
1564-1642

Fig. 2.5a
in Unit 1

A problem in *space-time* : (60mph Cell-faxing 4ton SUV rear-ends 10mph 1ton VW)

Geometry of Galilean translation (A symmetry transformation)

If you increase your velocity by 50 mph,... *(In some direction x,y, or z…)*

*…the rest of the world appears to be 50 mph **slower*** *(In that direction…)*

(a) Galileo transforms to COM frame

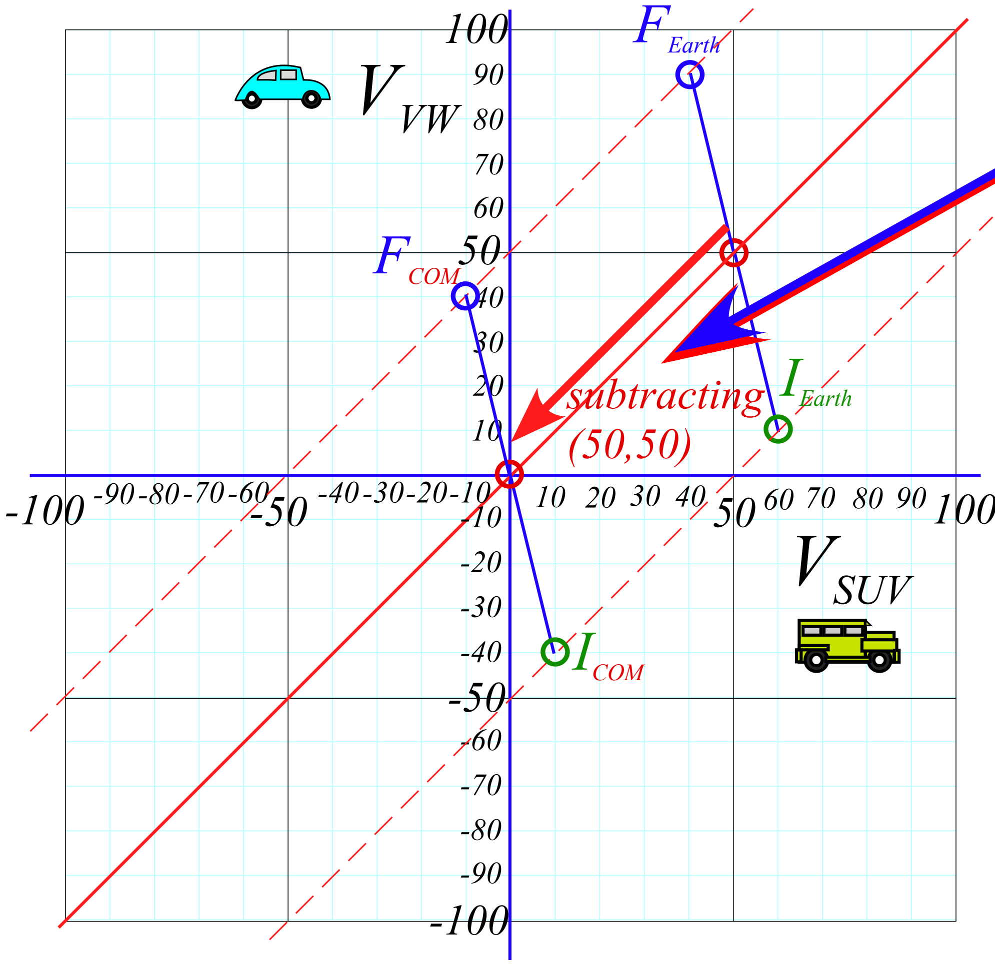


Fig. 2.5a
in Unit 1

(b) … and to five or six other reference frames

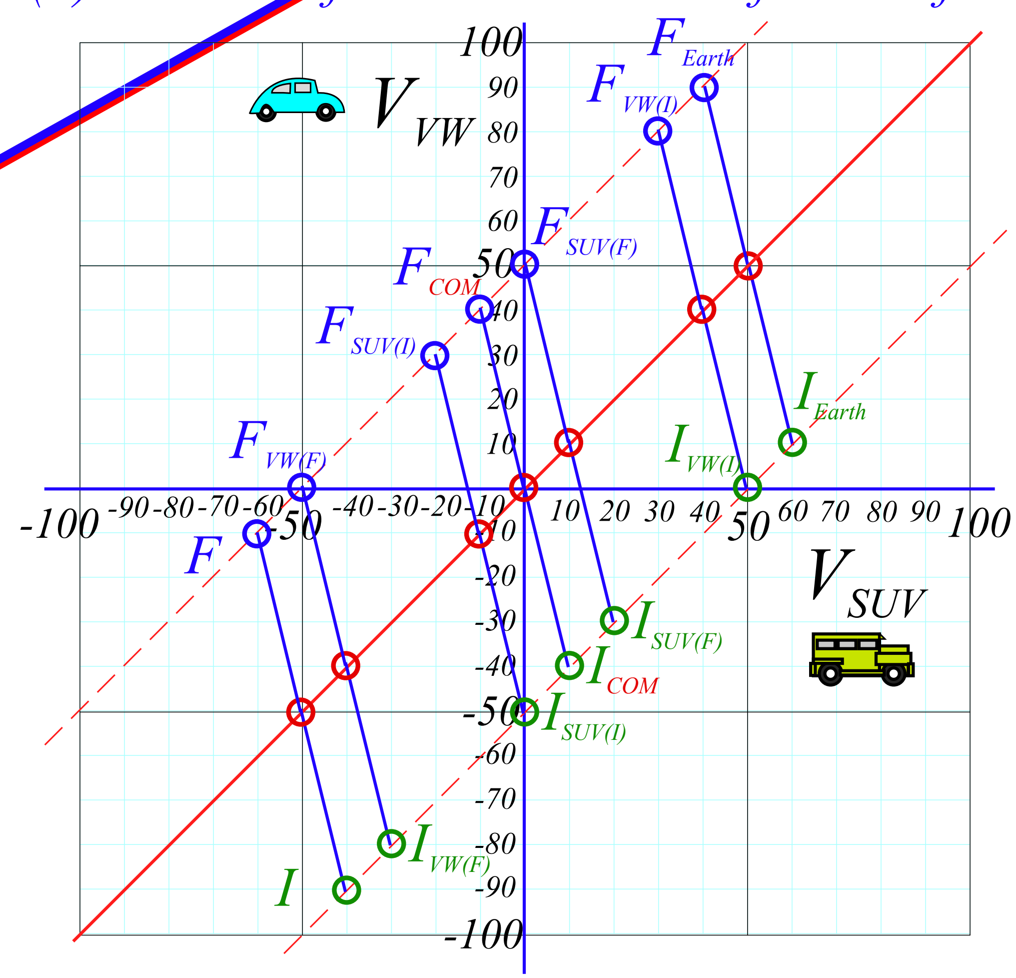
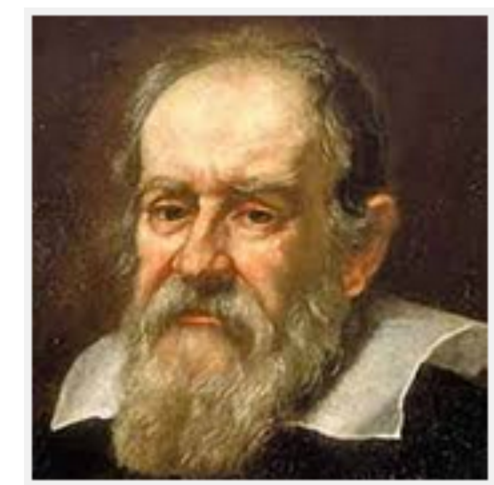


Fig. 2.5b
in Unit 1



Galileo Galilei
1564-1642

(Five of these have *0* for a velocity coord.)

Geometry of Galilean translation symmetry

45° shift in (V_1,V_2)-space

→ *Time reversal symmetry*

...of COM collisions

A problem in *space-time* : (60mph Cell-faxing 4ton SUV rear-ends 10mph 1ton VW)

Geometry of Galilean translation (A symmetry transformation)

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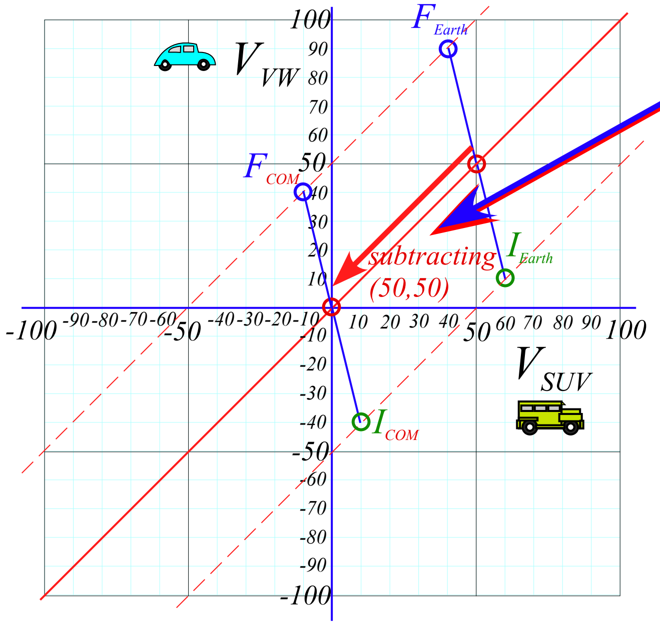


Fig. 2.5a
in Unit 1

(b) ... and to five or six other reference frames

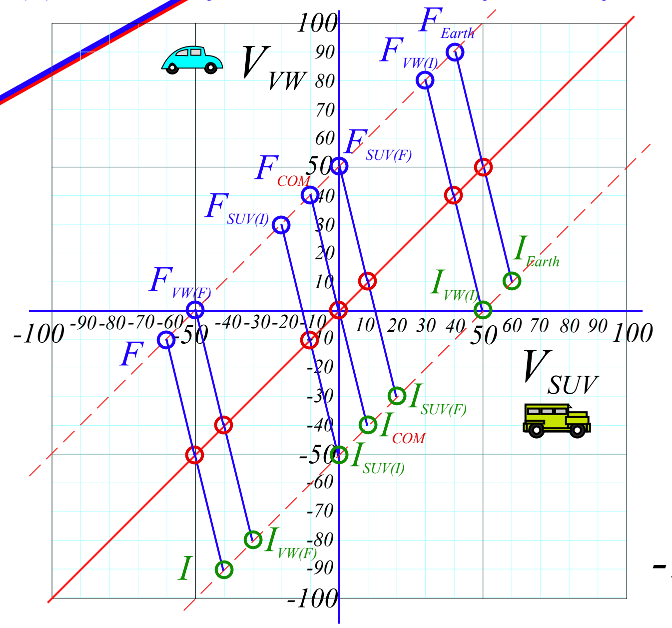
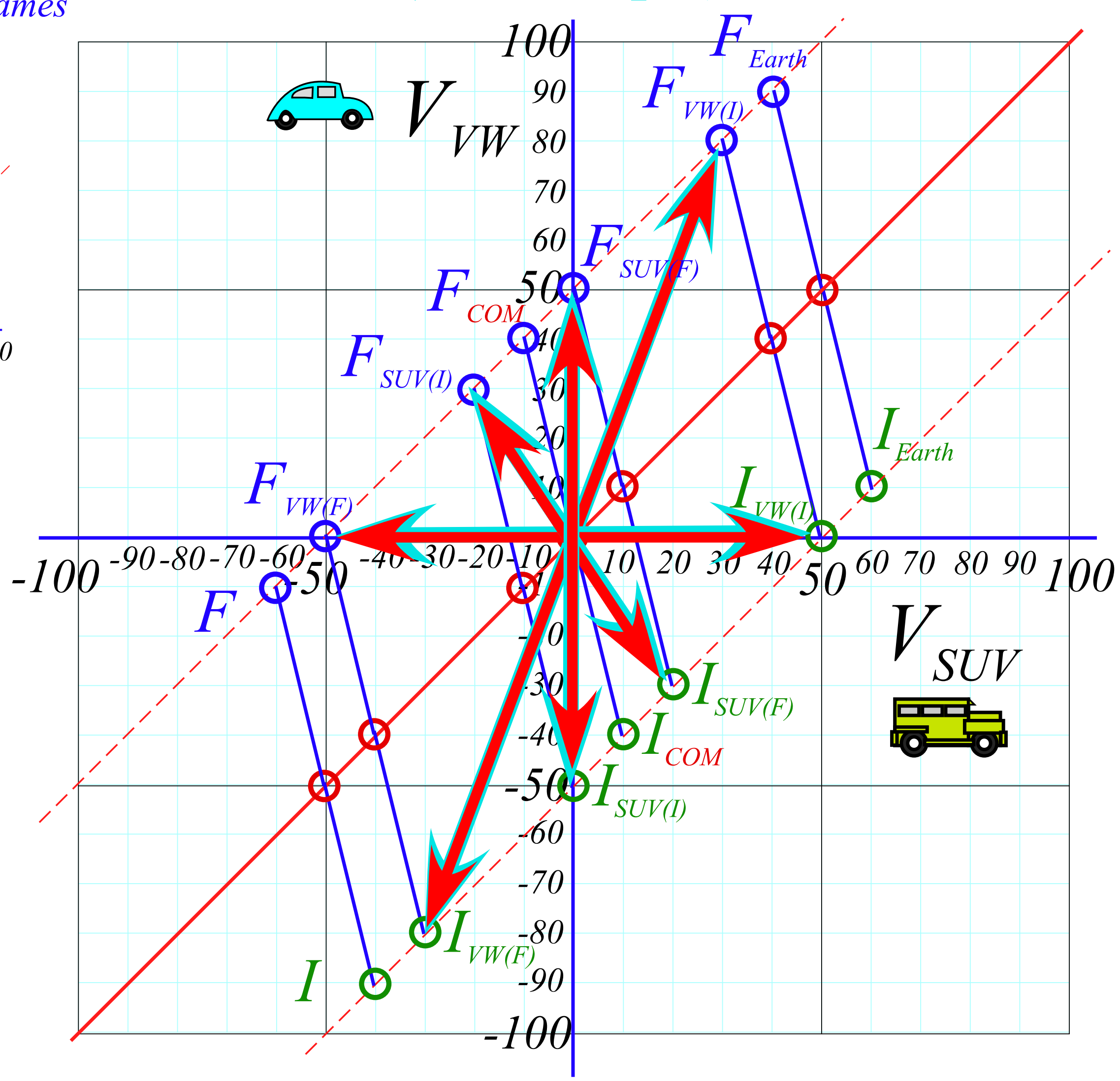


Fig. 2.5b
in Unit 1

Final F and Initial I trade places...

Time-reversal (F-I) symmetry pairs (Four examples)



Time-reversal means flip t to -t...
(Run a movie backwards)

A problem in *space-time* : (60mph Cell-faxing 4ton SUV rear-ends 10mph 1ton VW)

Geometry of Galilean translation (A symmetry transformation)

If you increase your velocity by 50 mph,...

*...the rest of the world appears to be 50 mph **slower***

(a) Galileo transforms to COM frame

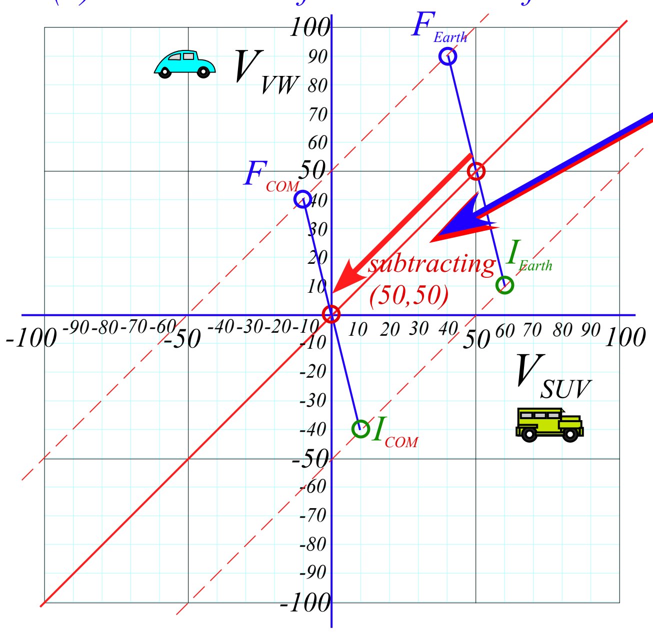


Fig. 2.5a
in Unit 1

(b) ... and to five or six other reference frames

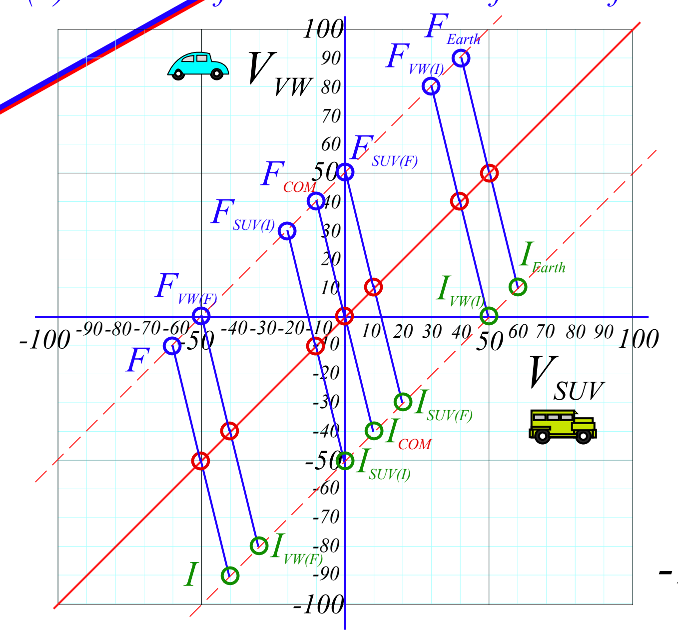
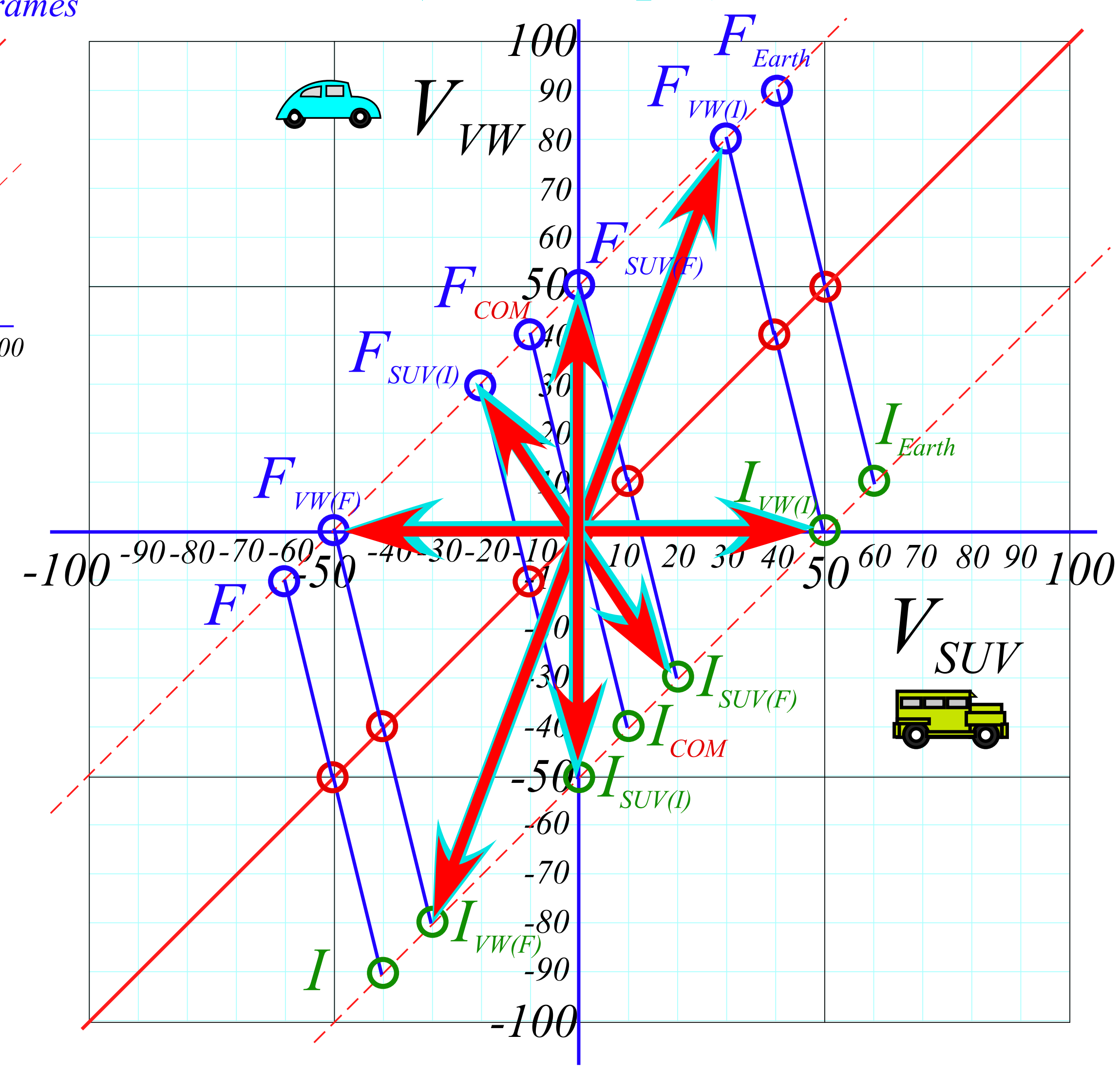


Fig. 2.5b
in Unit 1

Final F and Initial I trade places...

Time-reversal (F-I) symmetry pairs (Four examples)



Time-reversal means flip t to -t...
(Run a movie backwards)

That means you flip Velocity V to -V...
(Everything goes backwards)

Geometry of Galilean translation symmetry

45° shift in (V_1,V_2)-space

Time reversal symmetry

→ *...of COM collisions*

A problem in *space-time* : (60mph Cell-faxing 4ton SUV rear-ends 10mph 1ton VW)

Geometry of Galilean translation (A symmetry transformation)

If you increase your velocity by 50 mph,...

*...the rest of the world appears to be 50 mph **slower***

THE

COM Time-reversal symmetry pair (Just 1 case)

(a) Galileo transforms to COM frame

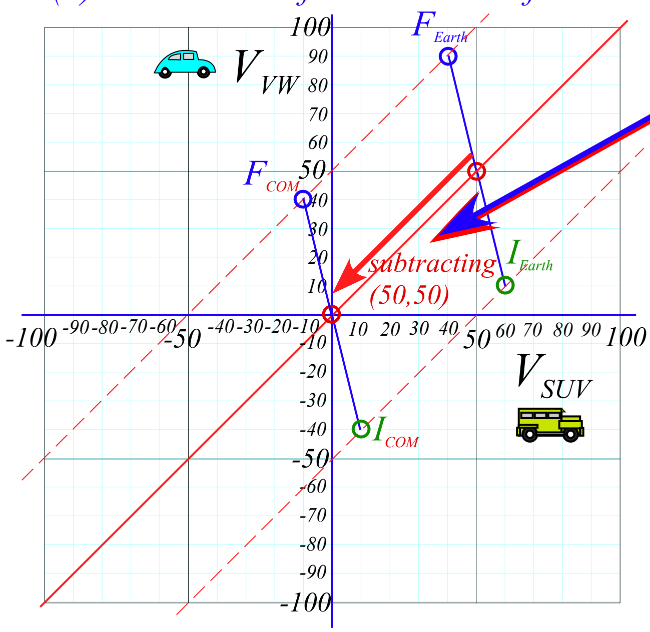


Fig. 2.5a
in Unit 1

(b) ... and to five or six other reference frames

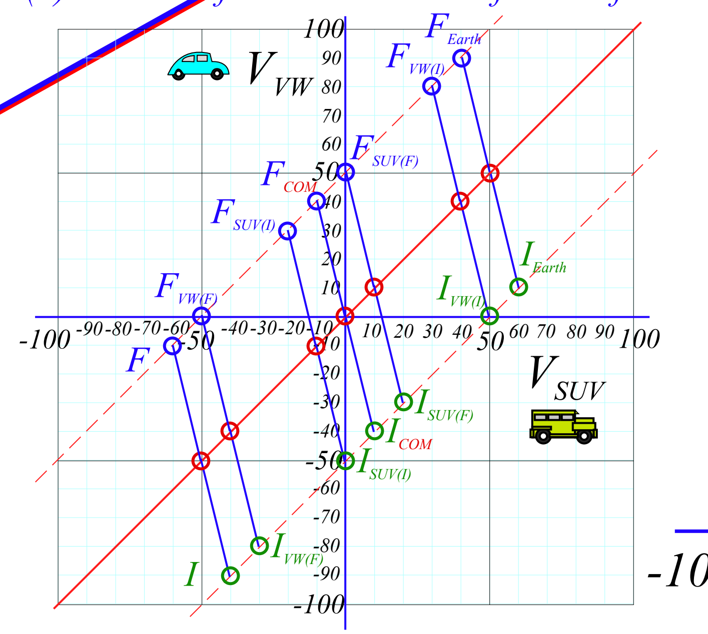
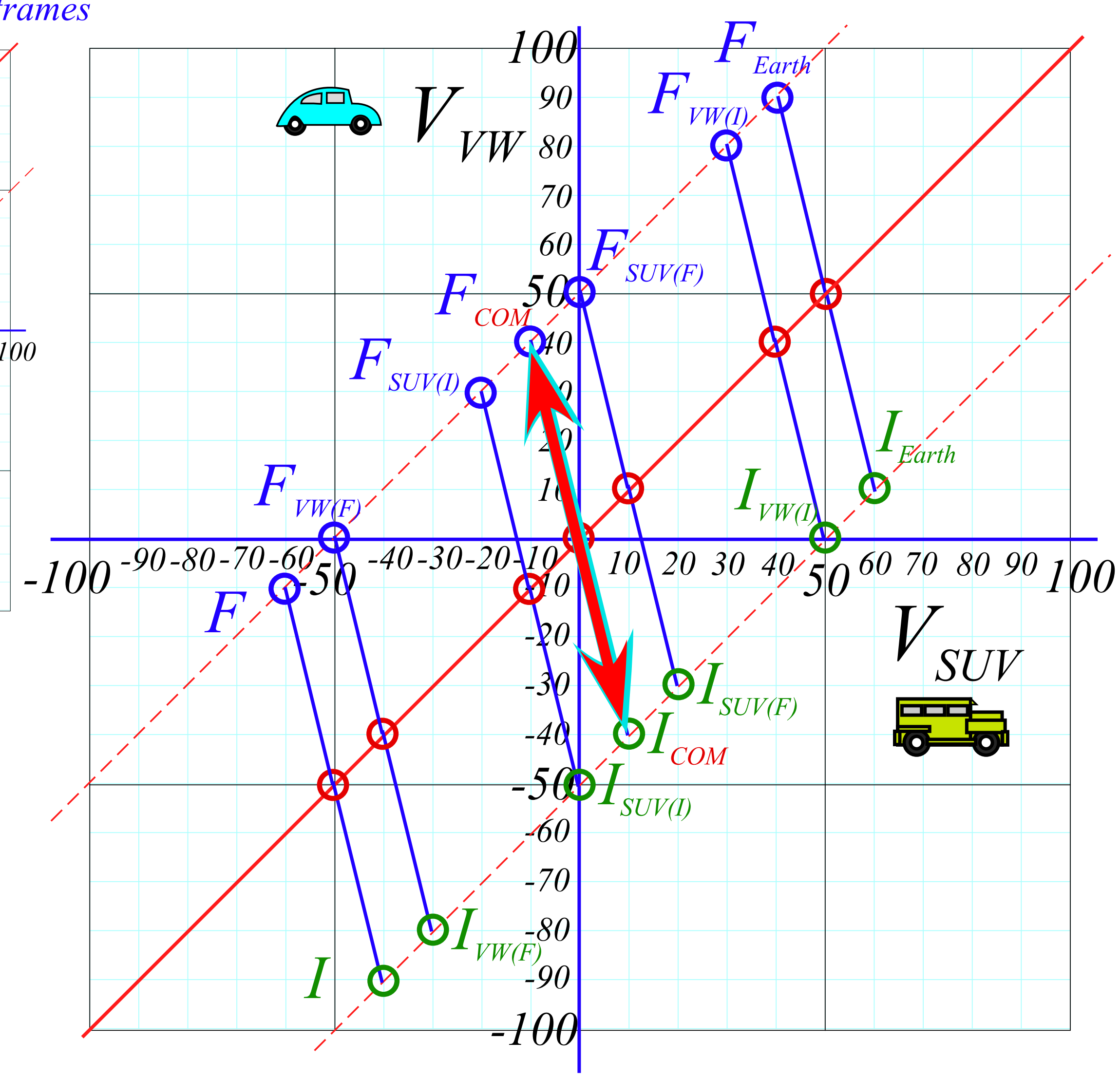


Fig. 2.5b
in Unit 1



There is just one velocity frame in which the time-reversed collision looks just like the original collision

That is the
Center-of-Momentum
***(COM)**-frame*

Time-reversal means flip t to -t…
(Run a movie backwards)

That means you flip Velocity V to -V…
(Everything goes backwards)

Algebra, Geometry, and Physics of momentum conservation axiom

→ *Vector algebra of collisions*
Matrix or tensor algebra of collisions
Deriving Energy Conservation Theorem
Energy Ellipse geometry

Quick lesson on

Gibb's notation for

dot (•) product of matrix operator **M** and column vector $\mathbf{V}^{IN}$:

$$\overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{IN}$$

$$\begin{pmatrix} A & B \\ C & D \end{pmatrix} \bullet \begin{pmatrix} x^{IN} \\ y^{IN} \end{pmatrix}$$

$$= \begin{pmatrix} Ax^{IN} + By^{IN} \\ Cx^{IN} + Dy^{IN} \end{pmatrix}$$

Algebra, Geometry, and Physics of momentum conservation axiom

- *Vector algebra of collisions*
- *Matrix or tensor algebra of collisions*
- *Deriving Energy Conservation Theorem*
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Quick lesson on
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$$= \begin{pmatrix} Ax^{IN} + By^{IN} \\ Cx^{IN} + Dy^{IN} \end{pmatrix}$$

Quick lesson on
Dirac notation is
much simpler:
$M|IN\rangle$

$$\begin{pmatrix} A & B \\ C & D \end{pmatrix} \begin{pmatrix} \langle x|IN\rangle \\ \langle y|IN\rangle \end{pmatrix}$$

Algebra, Geometry, and Physics of momentum conservation axiom

→ *Vector algebra of collisions*
Matrix or tensor algebra of collisions
Deriving Energy Conservation Theorem
Energy Ellipse geometry

Quick lesson on
Gibb's notation for
dot (•) product of matrix operator **M** and column vector $\mathbf{V}^{IN}$:

$$\overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{IN}$$

$$\begin{pmatrix} A & B \\ C & D \end{pmatrix} \bullet \begin{pmatrix} x^{IN} \\ y^{IN} \end{pmatrix}$$

$$= \begin{pmatrix} Ax^{IN} + By^{IN} \\ Cx^{IN} + Dy^{IN} \end{pmatrix}$$

Quick lesson on
Dirac notation is
much simpler:

$M|IN\rangle$ (...at first!)

$$\begin{pmatrix} \langle x|M|x\rangle & \langle x|M|y\rangle \\ \langle y|M|x\rangle & \langle y|M|y\rangle \end{pmatrix} \begin{pmatrix} \langle x|IN\rangle \\ \langle y|IN\rangle \end{pmatrix}$$

$$= \begin{pmatrix} \langle x|M|x\rangle\langle x|IN\rangle + \langle x|M|y\rangle\langle y|IN\rangle \\ \langle y|M|x\rangle\langle x|IN\rangle + \langle y|M|y\rangle\langle y|IN\rangle \end{pmatrix}$$

Algebra, Geometry, and Physics of momentum conservation axiom

- → *Vector algebra of collisions*
- *Matrix or tensor algebra of collisions*
- *Deriving Energy Conservation Theorem*
- *Energy Ellipse geometry*

General **Inertia Tensor M** or inertia matrix of *2* coefficients $M_{11}=M_1$ and $M_{22}=M_2$ for 2 dimensions

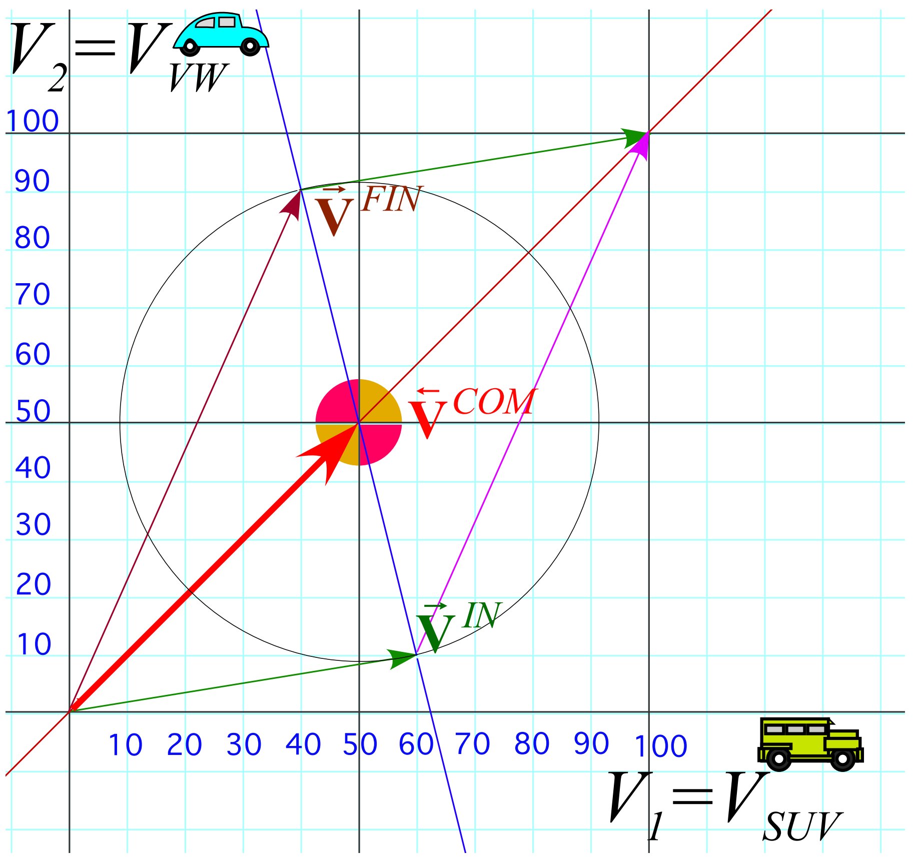
$$\left.\begin{array}{l} P_1 = M_1V_1 + M_{12}V_2 \\ P_2 = M_{21}V_1 + M_2V_2 \end{array}\right\} \quad denoted: \vec{\mathbf{P}} = \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}} \quad or: \begin{pmatrix} P_1 \\ P_2 \end{pmatrix} = \begin{pmatrix} M_1 & 0 \\ 0 & M_2 \end{pmatrix}\begin{pmatrix} V_1 \\ V_2 \end{pmatrix}$$

Generalizing the definition of *momentum*...

With 45° diagonal $\mathbf{V}^{COM}$ so: . $V_1^{COM} = V_2^{COM} \equiv V^{COM}$

...and 3 ways to write *Axiom-1*

$$P_{Total} = M_1V_1^{IN}+M_2V_2^{IN} = M_1V_1^{FIN}+M_2V_2^{FIN} = M_1V^{COM}+M_2V^{COM} = (M_1+M_2)V^{COM} = M_{Total}V^{COM}$$



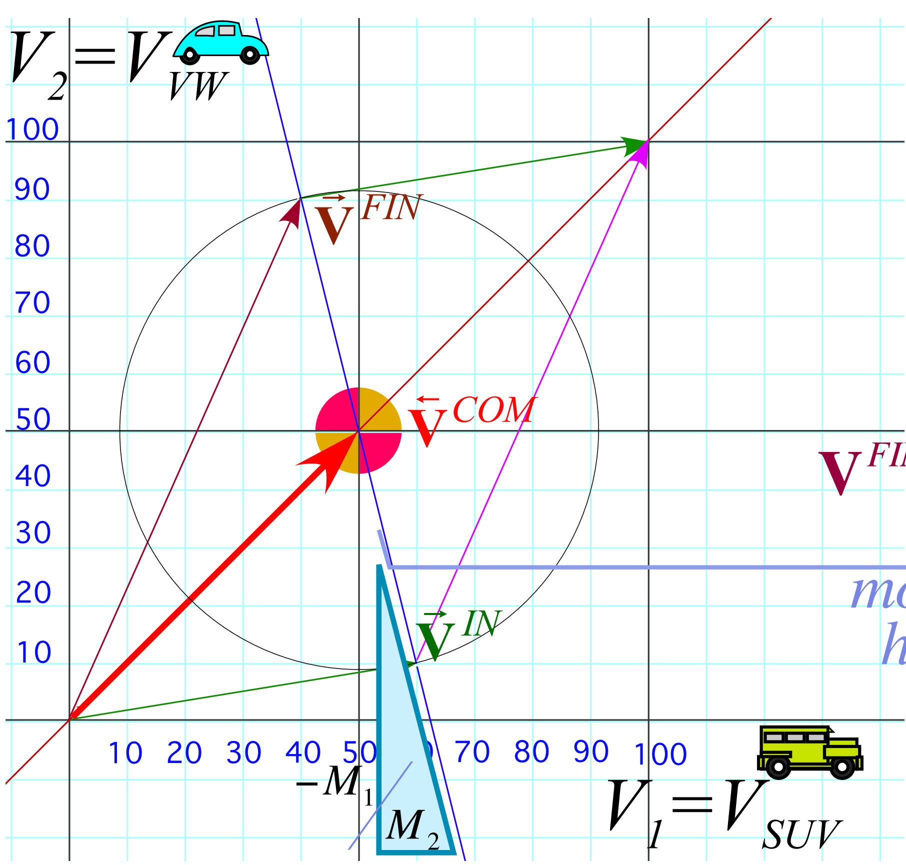
General **Inertia Tensor M** or inertia matrix of *2* coefficients $M_{11}=M_1$ and $M_{22}=M_2$ for 2 dimensions

$$\left.\begin{aligned} P_1 &= M_1V_1 + M_{12}V_2 \\ P_2 &= M_{21}V_1 + M_2V_2 \end{aligned}\right\} \quad denoted: \vec{\mathbf{P}} = \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}} \quad or: \begin{pmatrix} P_1 \\ P_2 \end{pmatrix} = \begin{pmatrix} M_1 & 0 \\ 0 & M_2 \end{pmatrix} \begin{pmatrix} V_1 \\ V_2 \end{pmatrix}$$

Generalizing the definition of *momentum*...

With 45° diagonal $\mathbf{V}^{COM}$ so: . $V_1^{COM} = V_2^{COM} \equiv V^{COM}$ ...and 3 ways to write *Axiom-1*

$$P_{Total} = M_1V_1^{IN} + M_2V_2^{IN} = M_1V_1^{FIN} + M_2V_2^{FIN} = M_1V^{COM} + M_2V^{COM} = (M_1+M_2)V^{COM} = M_{Total}V^{COM}$$



Points of vectors $\mathbf{V}^{FIN}$ and $\mathbf{V}^{COM}$ and $\mathbf{V}^{IN}$ all lie on

momentum - conservation line having slope $-M_1 / M_1$

General Inertia Tensor M or inertia matrix of *3* coefficients M_{11}, M_{22} and $M_{12}=M_{21}$ for 2 dimensions

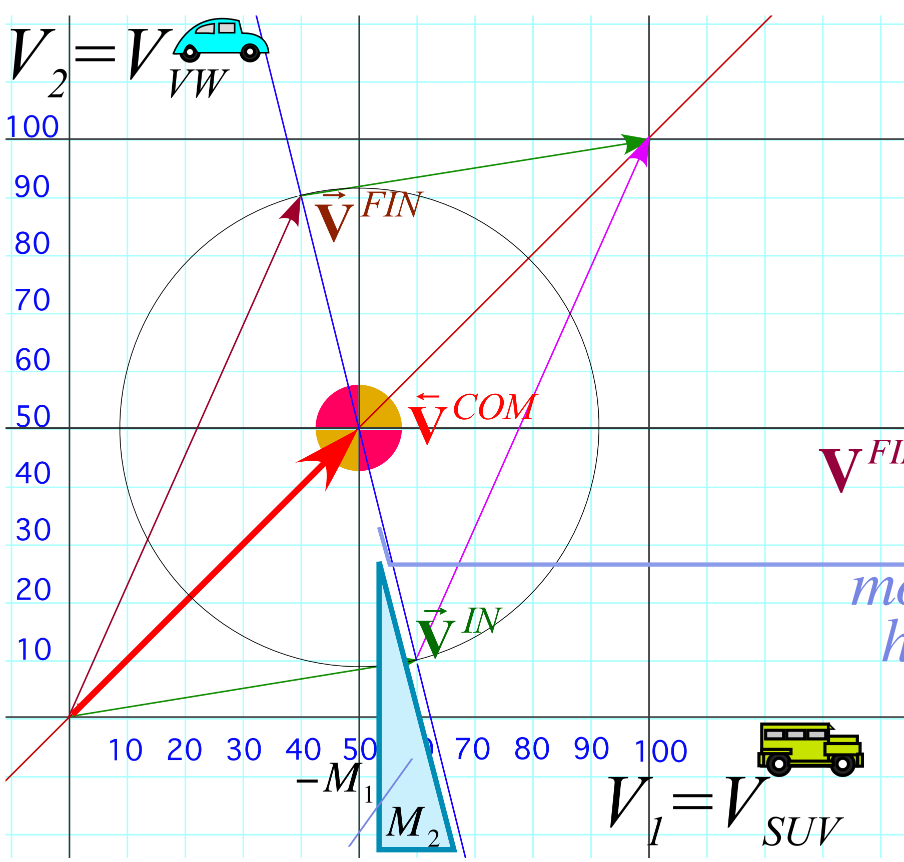
$$\left.\begin{array}{l} P_1 = M_{11}V_1 + M_{12}V_2 \\ P_2 = M_{21}V_1 + M_{22}V_2 \end{array}\right\} \quad denoted: \vec{\mathbf{P}} = \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}} \quad or: \begin{pmatrix} P_1 \\ P_2 \end{pmatrix} = \begin{pmatrix} M_{11} & M_{12} \\ M_{12} & M_{22} \end{pmatrix} \begin{pmatrix} V_1 \\ V_2 \end{pmatrix}$$

Generalizing the definition of *momentum*...some more...

With 45° diagonal $\mathbf{V}^{COM}$ so: . $V_1^{COM} = V_2^{COM} \equiv V^{COM}$

...and 3 ways to write *Axiom-1*

$$P_{Total} = M_1V_1^{IN} + M_2V_2^{IN} = M_1V_1^{FIN} + M_2V_2^{FIN} = M_1V^{COM} + M_2V^{COM} = (M_1+M_2)V^{COM} = M_{Total}V^{COM}$$



Points of vectors $\mathbf{V}^{FIN}$ and $\mathbf{V}^{COM}$ and $\mathbf{V}^{IN}$ all lie on *momentum - conservation line having slope* $- M_1 / M_1$

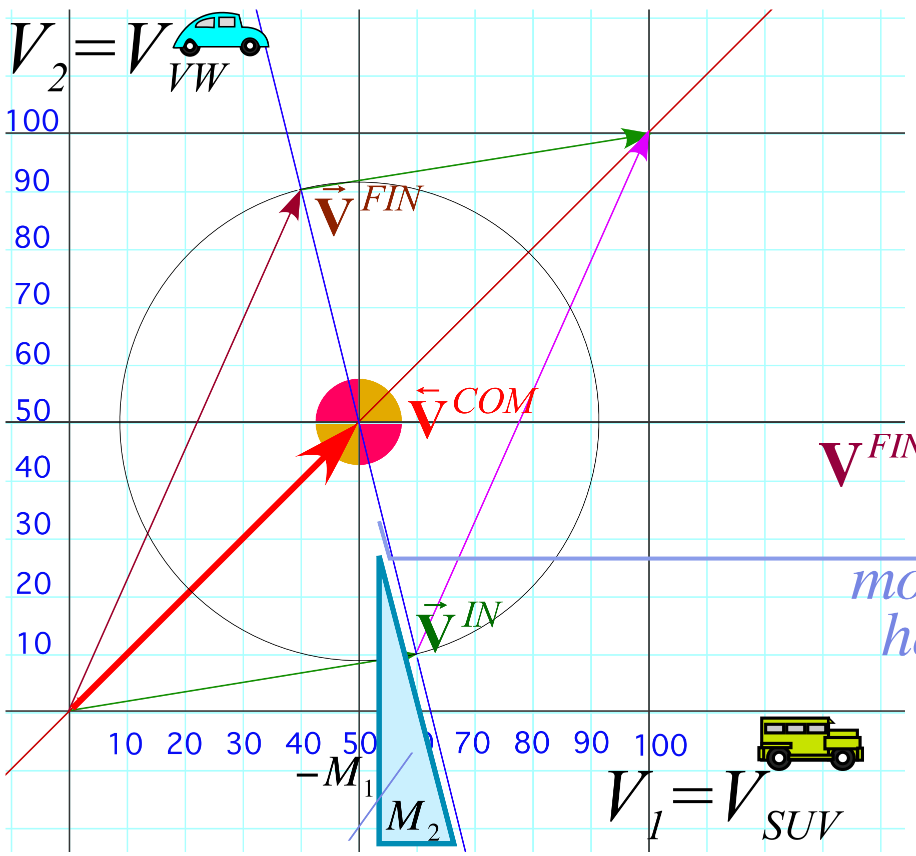
General Inertia Tensor M or inertia matrix of $(n^2+n)/2$ coefficients $M_{jk} = M_{kj}$ for dimension $n=2, 3, \ldots$

$$\left.\begin{array}{l} P_1 = M_{11}V_1 + M_{12}V_2 \cdots \\ P_2 = M_{21}V_1 + M_{22}V_2 \cdots \\ \vdots = \quad \vdots \qquad\quad \vdots \ \ \ddots \end{array}\right\} \quad denoted: \vec{\mathbf{P}} = \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}} \quad or: \begin{pmatrix} P_1 \\ P_2 \\ \vdots \end{pmatrix} = \begin{pmatrix} M_{11} & M_{12} & \cdots \\ M_{21} & M_{22} & \cdots \\ \vdots & \vdots & \ddots \end{pmatrix} \begin{pmatrix} V_1 \\ V_2 \\ \vdots \end{pmatrix}$$

Generalizing the definition of *momentum*...some more...and more

With 45°diagonal $\vec{\mathbf{V}}^{COM} = (\vec{\mathbf{V}}^{FIN} + \vec{\mathbf{V}}^{IN})/2$ so: $V_1^{COM} = V_2^{COM} \equiv V^{COM}$ ...and 3 ways to write *Axiom-1*

$$P_{Total} = M_1 V_1^{IN} + M_2 V_2^{IN} = M_1 V_1^{FIN} + M_2 V_2^{FIN} = M_1 V^{COM} + M_2 V^{COM} = (M_1 + M_2) V^{COM} = M_{Total} V^{COM}$$



Points of vectors $\mathbf{V}^{FIN}$ and $\mathbf{V}^{COM}$ and $\mathbf{V}^{IN}$ all lie on *momentum - conservation line having slope* $-M_1/M_1$

Algebra, Geometry, and Physics of momentum conservation axiom

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Generalizing the definition of *momentum*...

With 45°diagonal $\vec{\mathbf{V}}^{COM} = (\vec{\mathbf{V}}^{FIN} + \vec{\mathbf{V}}^{IN})/2$ so: $V_1^{COM} = V_2^{COM} \equiv V^{COM}$ ...and 4 or 5 ways to write *Axiom-1*

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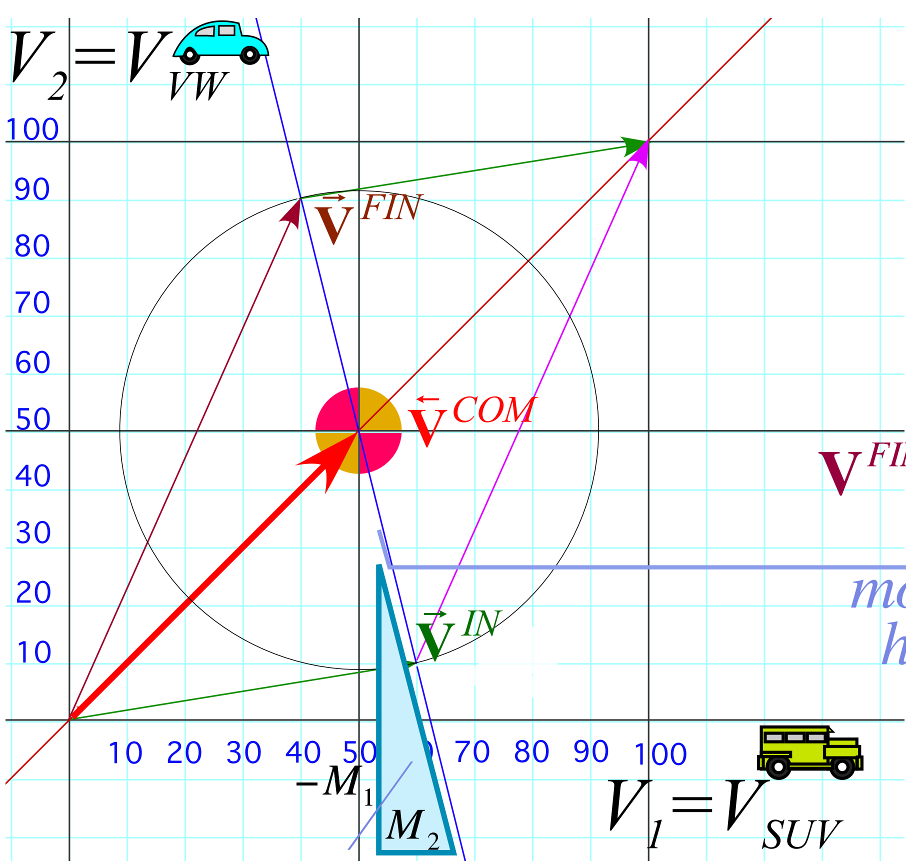

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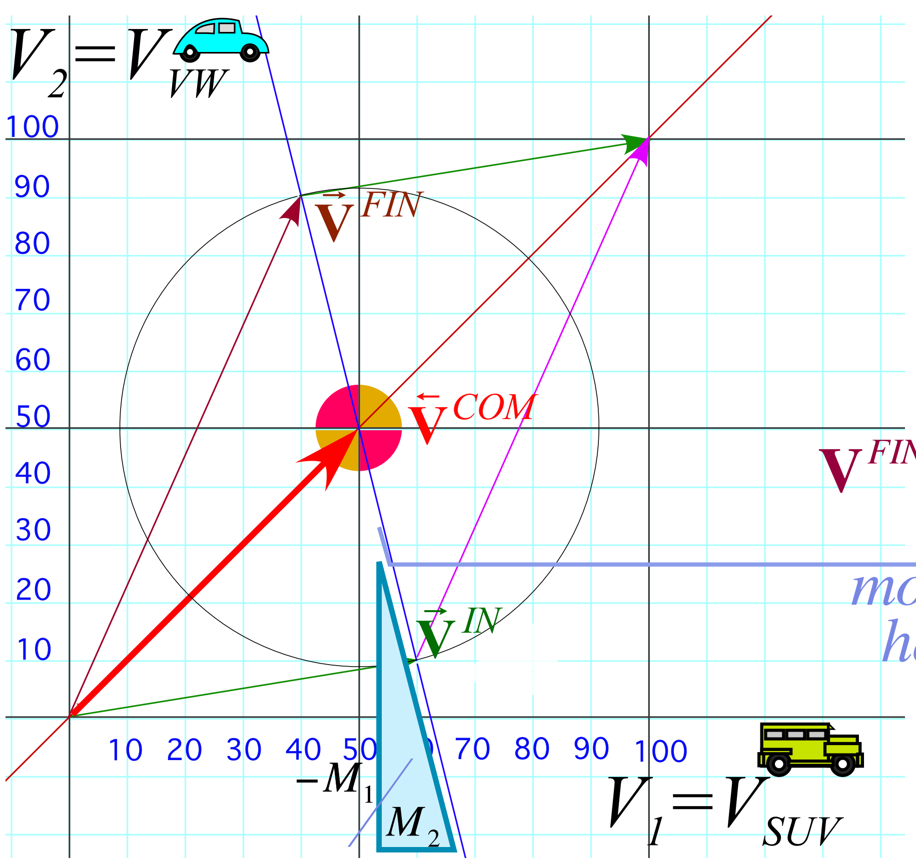
$$P_{Total} = M_1 V_1^{IN} + M_2 V_2^{IN} = M_1 V_1^{FIN} + M_2 V_2^{FIN} = M_1 V^{COM} + M_2 V^{COM} = (M_1 + M_2) V^{COM} = M_{Total} V^{COM}$$

A product of total momentum P_{Total} and V^{COM} is expressed by *tensor quadratic forms* **v•M•u**

$$V^{COM} P_{Total} = \vec{\mathbf{V}}^{COM} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{IN} = \vec{\mathbf{V}}^{COM} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{FIN} = \vec{\mathbf{V}}^{COM} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{COM} = V^{COM} M_{Total} V^{COM}$$



Points of vectors $\mathbf{V}^{FIN}$ and $\mathbf{V}^{COM}$ and $\mathbf{V}^{IN}$ all lie on *momentum - conservation line having slope* $-M_1 / M_1$

Numerical details of collision tensor algebra

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Generalizing the definition of *momentum*...

With 45°diagonal $\vec{\mathbf{V}}^{COM} = (\vec{\mathbf{V}}^{FIN} + \vec{\mathbf{V}}^{IN})/2$ so: $V_1^{COM} = V_2^{COM} \equiv V^{COM}$ ...and 4 or 5 ways to write *Axiom-1*

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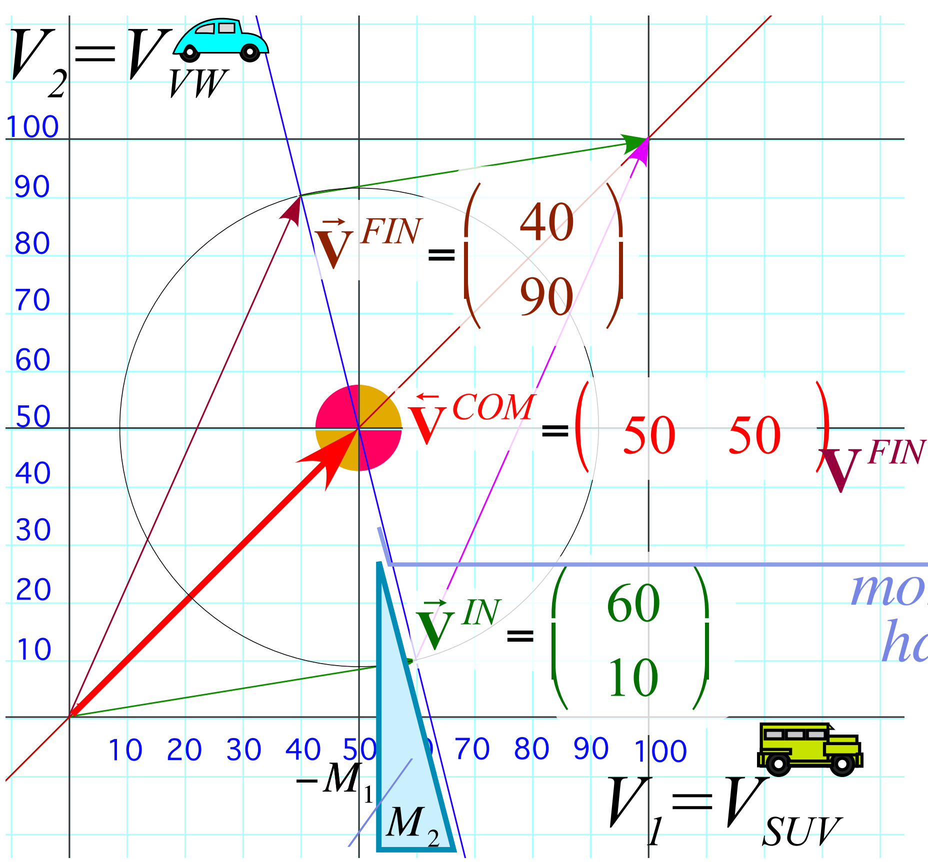
Write this out with the numbers used in Fig. 1.3 where $V^{COM} = 50$.

$$50 P_{Total} = \begin{pmatrix} 50 & 50 \end{pmatrix} \bullet \begin{pmatrix} 4 & 0 \\ 0 & 1 \end{pmatrix} \bullet \begin{pmatrix} 60 \\ 10 \end{pmatrix} = \begin{pmatrix} 50 & 50 \end{pmatrix} \bullet \begin{pmatrix} 4 & 0 \\ 0 & 1 \end{pmatrix} \bullet \begin{pmatrix} 40 \\ 90 \end{pmatrix} = 50 M_{Total} 50 = 12{,}500$$



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Generalizing the definition of *momentum*...

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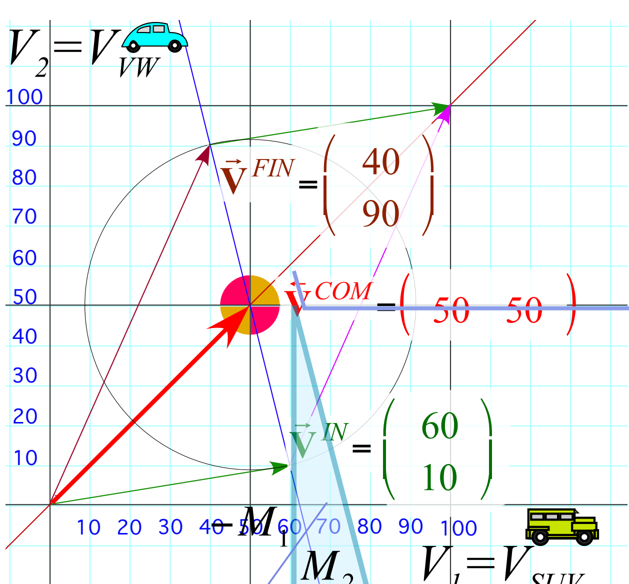
$$= \begin{pmatrix} 50 & 50 \end{pmatrix} \bullet \begin{pmatrix} 4\cdot 60 \\ 1\cdot 10 \end{pmatrix} \qquad = \begin{pmatrix} 50 & 50 \end{pmatrix} \bullet \begin{pmatrix} 4\cdot 40 \\ 1\cdot 90 \end{pmatrix} \qquad = 50M_{Total}50 = 12{,}500$$

$$50\cdot 250 = 50\cdot 4\cdot 60 + 50\cdot 1\cdot 10 \qquad = 50\cdot 4\cdot 40 + 50\cdot 1\cdot 90 \qquad = 50\cdot 5\cdot 50 = 12{,}500$$



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Generalizing the definition of *momentum*...

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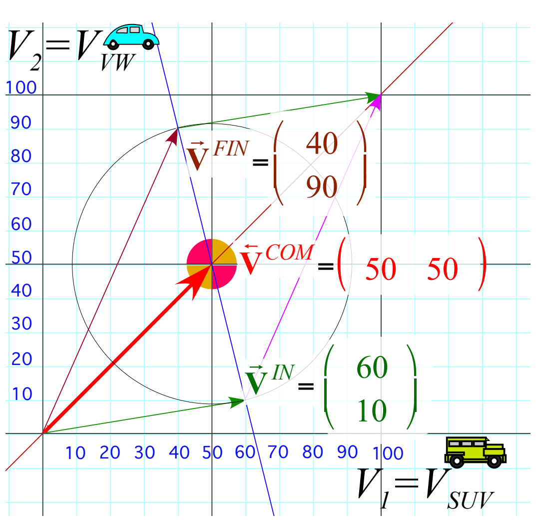
$$= 100 \cdot 125 \qquad = 100 \cdot 125 \qquad = 50 \cdot 250$$

P_{Total} *=250* is the same at IN, FIN, and COM. Now use *T*-symmetry: $\vec{\mathbf{V}}^{COM}=(\vec{\mathbf{V}}^{FIN}+\vec{\mathbf{V}}^{IN})/2$ ***(Axiom-2)***

$$V^{COM} P_{Total} = \frac{\vec{\mathbf{V}}^{FIN}+\vec{\mathbf{V}}^{IN}}{2} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{IN} = \frac{\vec{\mathbf{V}}^{FIN}+\vec{\mathbf{V}}^{IN}}{2} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{FIN} = \frac{\vec{\mathbf{V}}^{FIN}+\vec{\mathbf{V}}^{IN}}{2} \bullet \overleftrightarrow{\mathbf{M}} \bullet \frac{\vec{\mathbf{V}}^{FIN}+\vec{\mathbf{V}}^{IN}}{2}$$



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$$= 100\cdot125 \qquad = 100\cdot125 \qquad = 50\cdot250$$

$P_{Total}=250$ is the same at IN, FIN, and COM. Now use T-symmetry: $\vec{\mathbf{V}}^{COM}=(\vec{\mathbf{V}}^{FIN}+\vec{\mathbf{V}}^{IN})/2$ ***(Axiom-2)***

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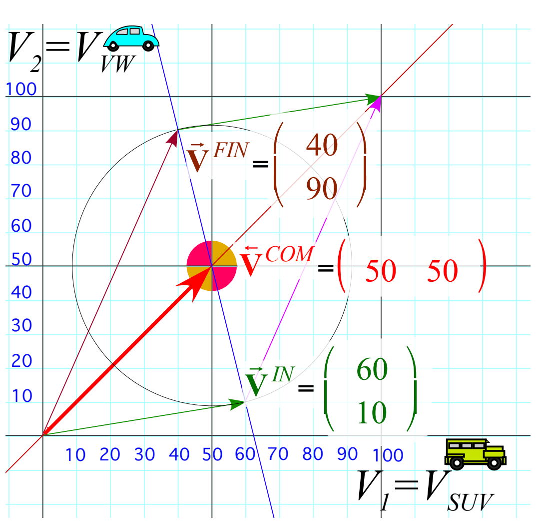
$$= \tfrac{1}{2}\vec{\mathbf{V}}^{FIN}\bullet\overleftrightarrow{\mathbf{M}}\bullet\vec{\mathbf{V}}^{IN}+\tfrac{1}{2}\vec{\mathbf{V}}^{IN}\bullet\overleftrightarrow{\mathbf{M}}\bullet\vec{\mathbf{V}}^{IN} = \tfrac{1}{2}\vec{\mathbf{V}}^{FIN}\bullet\overleftrightarrow{\mathbf{M}}\bullet\vec{\mathbf{V}}^{FIN}+\tfrac{1}{2}\vec{\mathbf{V}}^{IN}\bullet\overleftrightarrow{\mathbf{M}}\bullet\vec{\mathbf{V}}^{FIN}$$



Numerical details of collision tensor algebra

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$$= 100 \cdot 125 \qquad = 100 \cdot 125 \qquad = 50 \cdot 250$$

$P_{Total} = 250$ is the same at IN, FIN, and COM. Now use *T*-symmetry: $\vec{\mathbf{V}}^{COM} = (\vec{\mathbf{V}}^{FIN} + \vec{\mathbf{V}}^{IN})/2$ ***(Axiom-2)***

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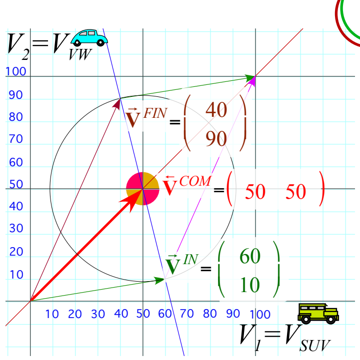
$$= \tfrac{1}{2} \vec{\mathbf{V}}^{FIN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{IN} + \tfrac{1}{2} \vec{\mathbf{V}}^{IN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{IN} \qquad = \tfrac{1}{2} \vec{\mathbf{V}}^{FIN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{FIN} + \tfrac{1}{2} \vec{\mathbf{V}}^{IN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{FIN}$$



Transpose symmetry ($M_{jk} = M_{kj}$) of **M**-matrix makes 'lopsided' FIN-IN-terms equal:

$$\vec{\mathbf{V}}^{FIN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{IN} = \vec{\mathbf{V}}^{IN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{FIN}$$

$$\begin{pmatrix} 40 & 90 \end{pmatrix} \bullet \begin{pmatrix} 4 & 0 \\ 0 & 1 \end{pmatrix} \bullet \begin{pmatrix} 60 \\ 10 \end{pmatrix} = \begin{pmatrix} 60 & 10 \end{pmatrix} \bullet \begin{pmatrix} 4 & 0 \\ 0 & 1 \end{pmatrix} \bullet \begin{pmatrix} 40 \\ 90 \end{pmatrix}$$

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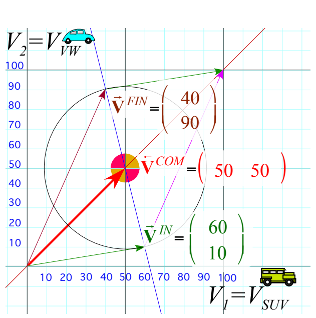
$$V^{COM}P_{Total} = \frac{\vec{\mathbf{V}}^{FIN}+\vec{\mathbf{V}}^{IN}}{2} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{IN} = \frac{\vec{\mathbf{V}}^{FIN}+\vec{\mathbf{V}}^{IN}}{2} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{FIN} = \frac{\vec{\mathbf{V}}^{FIN}+\vec{\mathbf{V}}^{IN}}{2} \bullet \overleftrightarrow{\mathbf{M}} \bullet \frac{\vec{\mathbf{V}}^{FIN}+\vec{\mathbf{V}}^{IN}}{2}$$

$$= \tfrac{1}{2}\vec{\mathbf{V}}^{FIN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{IN} + \tfrac{1}{2}\vec{\mathbf{V}}^{IN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{IN} = \tfrac{1}{2}\vec{\mathbf{V}}^{FIN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{FIN} + \tfrac{1}{2}\vec{\mathbf{V}}^{IN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{FIN}$$

$$V^{COM}P_{Total} - \tfrac{1}{2}\vec{\mathbf{V}}^{FIN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{IN} = \tfrac{1}{2}\vec{\mathbf{V}}^{IN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{IN} = \tfrac{1}{2}\vec{\mathbf{V}}^{FIN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{FIN}$$

FIN-IN-term is subtracted to give *Conservation of* ***Kinetic Energy***

$$KE = \tfrac{1}{2}\vec{\mathbf{V}} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}} = \tfrac{1}{2}M_1V_1^2 + \tfrac{1}{2}M_2V_2^2$$



$$\vec{\mathbf{V}}^{FIN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{IN} = \vec{\mathbf{V}}^{IN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{FIN}$$

$$\begin{pmatrix} 40 & 90 \end{pmatrix} \bullet \begin{pmatrix} 4 & 0 \\ 0 & 1 \end{pmatrix} \bullet \begin{pmatrix} 60 \\ 10 \end{pmatrix} = \begin{pmatrix} 60 & 10 \end{pmatrix} \bullet \begin{pmatrix} 4 & 0 \\ 0 & 1 \end{pmatrix} \bullet \begin{pmatrix} 40 \\ 90 \end{pmatrix}$$

$$= 100 \cdot 105 \qquad = 100 \cdot 105 \qquad = 10{,}500$$

General **Inertia Tensor M** or inertia matrix of 2 coefficients $M_{11}=M_1$ and $M_{22}=M_2$ for 2 dimensions

$$\left.\begin{array}{l} P_1 = M_1V_1 + M_{12}V_2 \\ P_2 = M_{21}V_1 + M_2V_2 \end{array}\right\} \quad denoted: \vec{\mathbf{P}} = \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}} \quad or: \begin{pmatrix} P_1 \\ P_2 \end{pmatrix} = \begin{pmatrix} M_1 & 0 \\ 0 & M_2 \end{pmatrix} \begin{pmatrix} V_1 \\ V_2 \end{pmatrix}$$

Generalizing the definition of *momentum*...

With 45°diagonal $\vec{\mathbf{V}}^{COM} = (\vec{\mathbf{V}}^{FIN} + \vec{\mathbf{V}}^{IN})/2$ so: $V_1^{COM} = V_2^{COM} \equiv V^{COM}$ ...and 4 or 5 ways to write ***Axiom-1***

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A product of total momentum P_{Total} and V^{COM} is expressed by *tensor quadratic forms* **v•M•u**

$$V^{COM}P_{Total} = \vec{\mathbf{V}}^{COM} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{IN} = \vec{\mathbf{V}}^{COM} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{FIN} = \vec{\mathbf{V}}^{COM} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{COM} = V^{COM}M_{Total}V^{COM}$$

Write this out with the numbers used in Fig. 1.3 where $V^{COM} = 50$.

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$50 \cdot 250 \; - ½ \cdot 10{,}500$

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With 45°diagonal $\vec{\mathbf{V}}^{COM}=(\vec{\mathbf{V}}^{FIN}+\vec{\mathbf{V}}^{IN})/2$ so: $V_1^{COM}=V_2^{COM}\equiv V^{COM}$ ...and 4 or 5 ways to write ***Axiom-1***

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50·250 -½·10,500
12,500 - 5,250

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$$V^{COM}P_{Total}-\tfrac{1}{2}\vec{\mathbf{V}}^{FIN}\bullet\overleftrightarrow{\mathbf{M}}\bullet\vec{\mathbf{V}}^{IN} = \tfrac{1}{2}\vec{\mathbf{V}}^{IN}\bullet\overleftrightarrow{\mathbf{M}}\bullet\vec{\mathbf{V}}^{IN} = \tfrac{1}{2}\vec{\mathbf{V}}^{FIN}\bullet\overleftrightarrow{\mathbf{M}}\bullet\vec{\mathbf{V}}^{FIN}$$

50·250 -½·10,500

12,500 - 5,250=7,250

$$\tfrac{1}{2}\vec{\mathbf{V}}^{IN}\bullet\overleftrightarrow{\mathbf{M}}\bullet\vec{\mathbf{V}}^{IN} = \tfrac{1}{2}\vec{\mathbf{V}}^{FIN}\bullet\overleftrightarrow{\mathbf{M}}\bullet\vec{\mathbf{V}}^{FIN}$$

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$$=\tfrac{1}{2}(60\cdot 4\cdot 60+10\cdot 1\cdot 10) = \tfrac{1}{2}(40\cdot 4\cdot 40+90\cdot 1\cdot 90)$$

$$2\cdot 3600 + 50 = 7250 = 2\cdot 1600 + \tfrac{1}{2}8100 = 7250$$

FIN-IN-term is subtracted to give *Conservation of* ***Kinetic Energy***

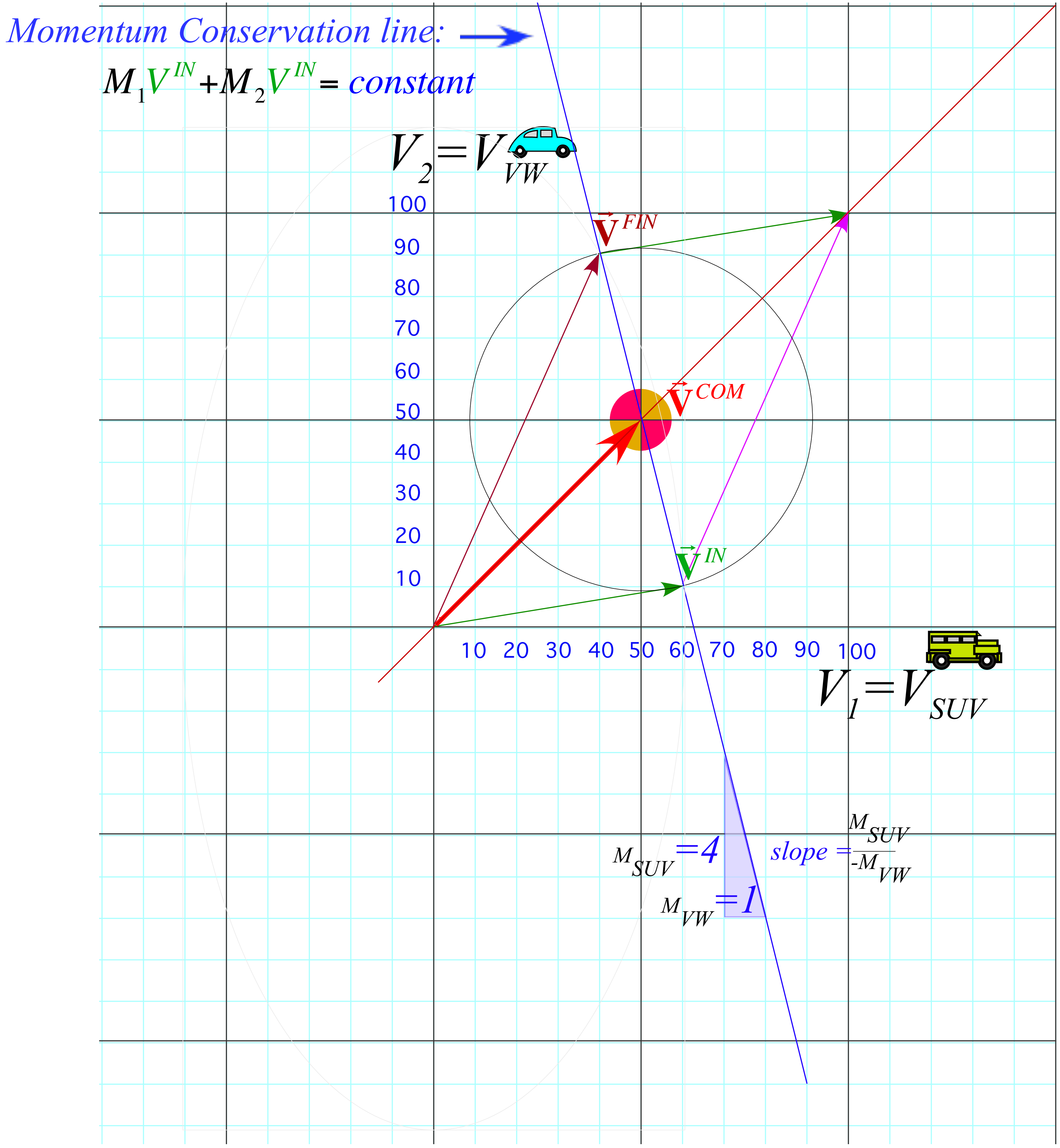
$$KE = \tfrac{1}{2}\vec{\mathbf{V}}\bullet\overleftrightarrow{\mathbf{M}}\bullet\vec{\mathbf{V}} = \tfrac{1}{2}M_1V_1^2+\tfrac{1}{2}M_2V_2^2$$

Algebra, Geometry, and Physics of momentum conservation axiom

- *Vector algebra of collisions*
- *Matrix or tensor algebra of collisions*
- *Deriving Energy Conservation Theorem*
- → *Energy Ellipse geometry*

Geometry of Momentum Conservation **Axiom - 1**

$$(M_1+M_2)V^{COM}=M_1V_1^{IN}+M_2V_2^{IN}=M_1V_1^{FIN}+M_2V_2^{FIN}$$



Collision *Web Simulator*
[***Basic elastic Collision Dual Panel Space vs Space and V(VW) vs. V(SUV)***]

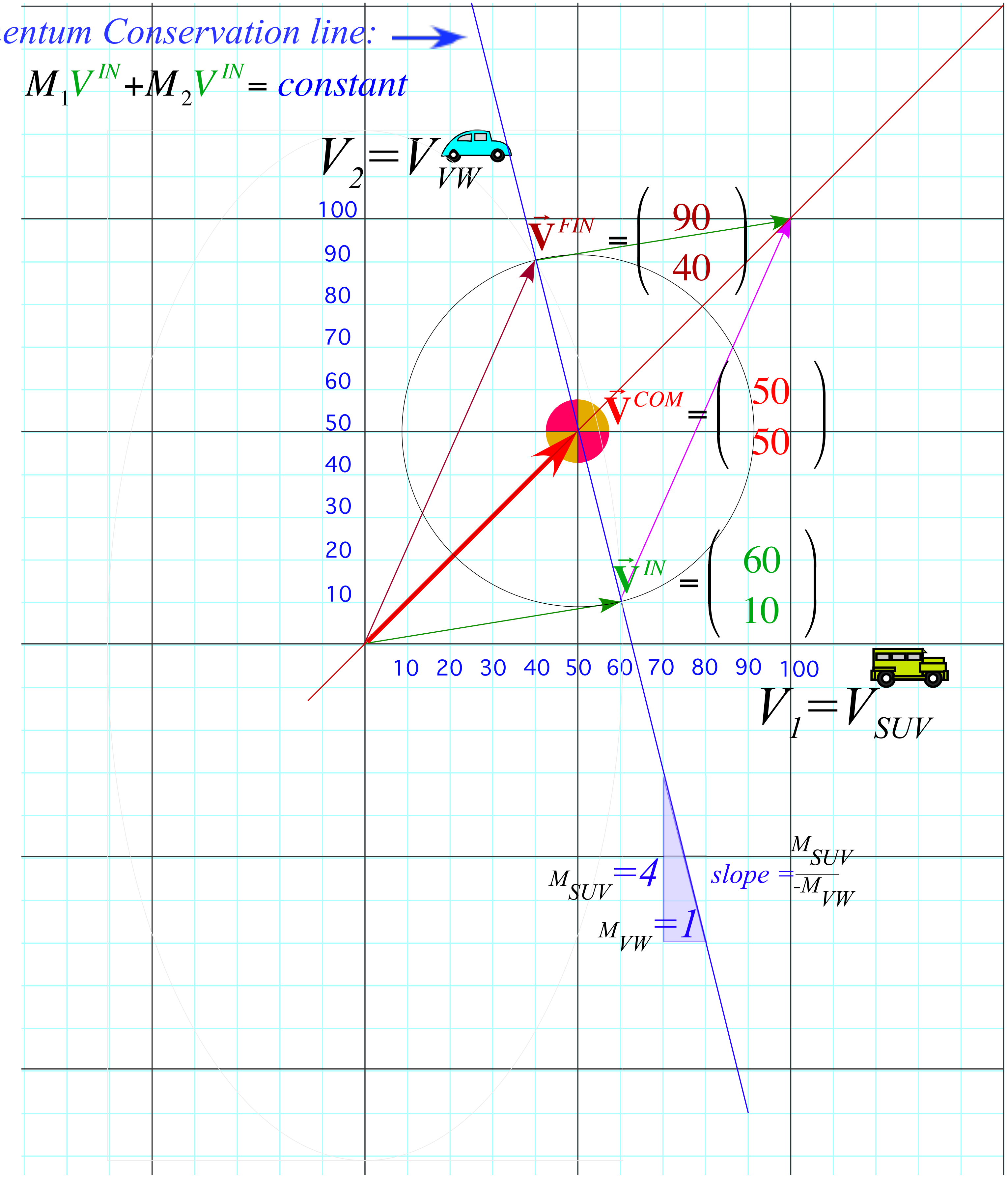
BounceIt
Superball Web Simulator
[***Basic elastic Collision Dual Panel Space vs Space and V(VW) vs. V(SUV)***]

Geometry of Momentum Conservation **Axiom - 1**

$$(M_1+M_2)V^{COM} = M_1 V_1^{IN} + M_2 V_2^{IN} = M_1 V_1^{FIN} + M_2 V_2^{FIN}$$

Momentum Conservation line: →

$$M_1 V^{IN} + M_2 V^{IN} = constant$$



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[*Dual Panel*]
[*Space vs Space*]
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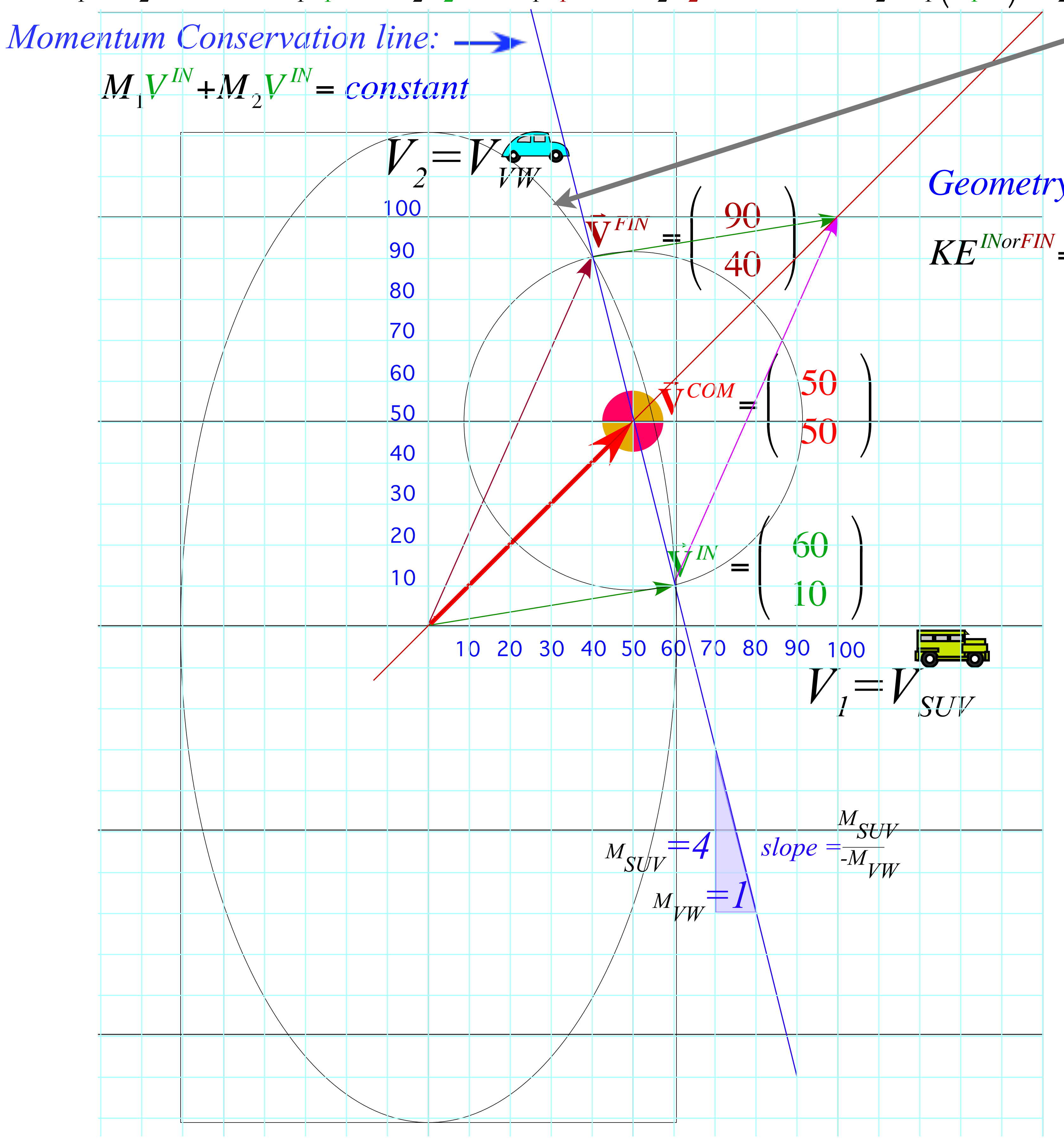
Geometry of Momentum Conservation **Axiom - 1**

$$(M_1+M_2)V^{COM}=M_1V_1^{IN}+M_2V_2^{IN}=M_1V_1^{FIN}+M_2V_2^{FIN}$$

Geometry of Kinetic Energy Conservation **Axiom-2/Theorem-1**

$$KE^{IN}=\tfrac{1}{2}M_1\left(V_1^{IN}\right)^2+\tfrac{1}{2}M_2\left(V_2^{IN}\right)^2=\tfrac{1}{2}M_1\left(V_1^{FIN}\right)^2+\tfrac{1}{2}M_2\left(V_2^{FIN}\right)^2=KE^{FIN}$$



Geometry of KE Conservation **Theorem - 1**

$$KE^{INorFIN}=\tfrac{1}{2}M_1\left(V_1\right)^2+\tfrac{1}{2}M_2\left(V_2\right)^2=\tfrac{1}{2}4\left(60\right)^2+\tfrac{1}{2}1\left(10\right)^2=7{,}250$$

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Momentum Conservation line: →

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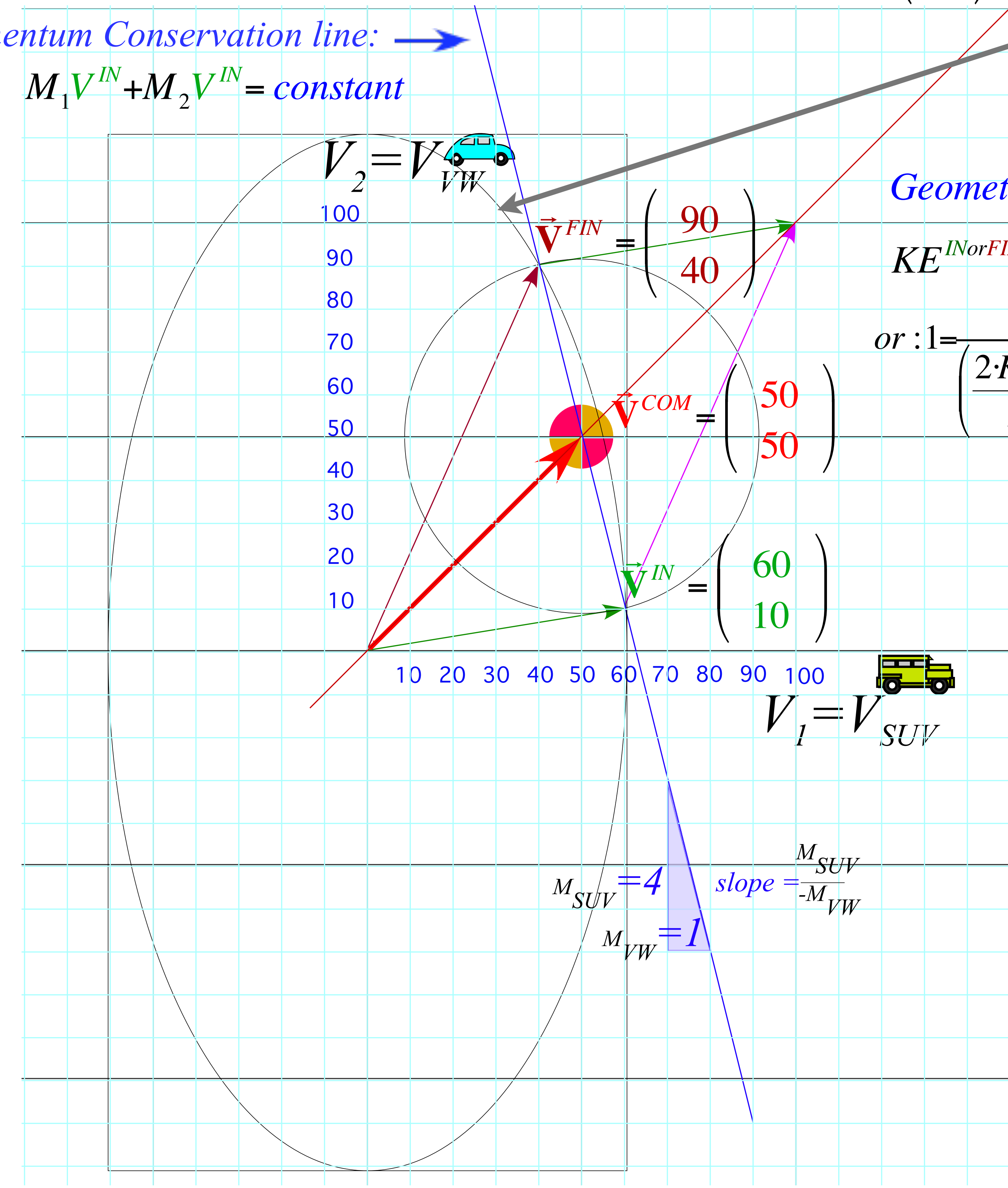
KE Conservation ellipse:



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$$or:1=\frac{V_1^2}{\left(\frac{2\cdot KE^{IFN}}{M_1}\right)}+\frac{V_2^2}{\left(\frac{2\cdot KE^{IFN}}{M_2}\right)}=\frac{V_1^2}{\left(\sqrt{\frac{2\cdot KE^{IFN}}{M_1}}\right)^2}+\frac{V_2^2}{\left(\sqrt{\frac{2\cdot KE^{IFN}}{M_2}}\right)^2}$$

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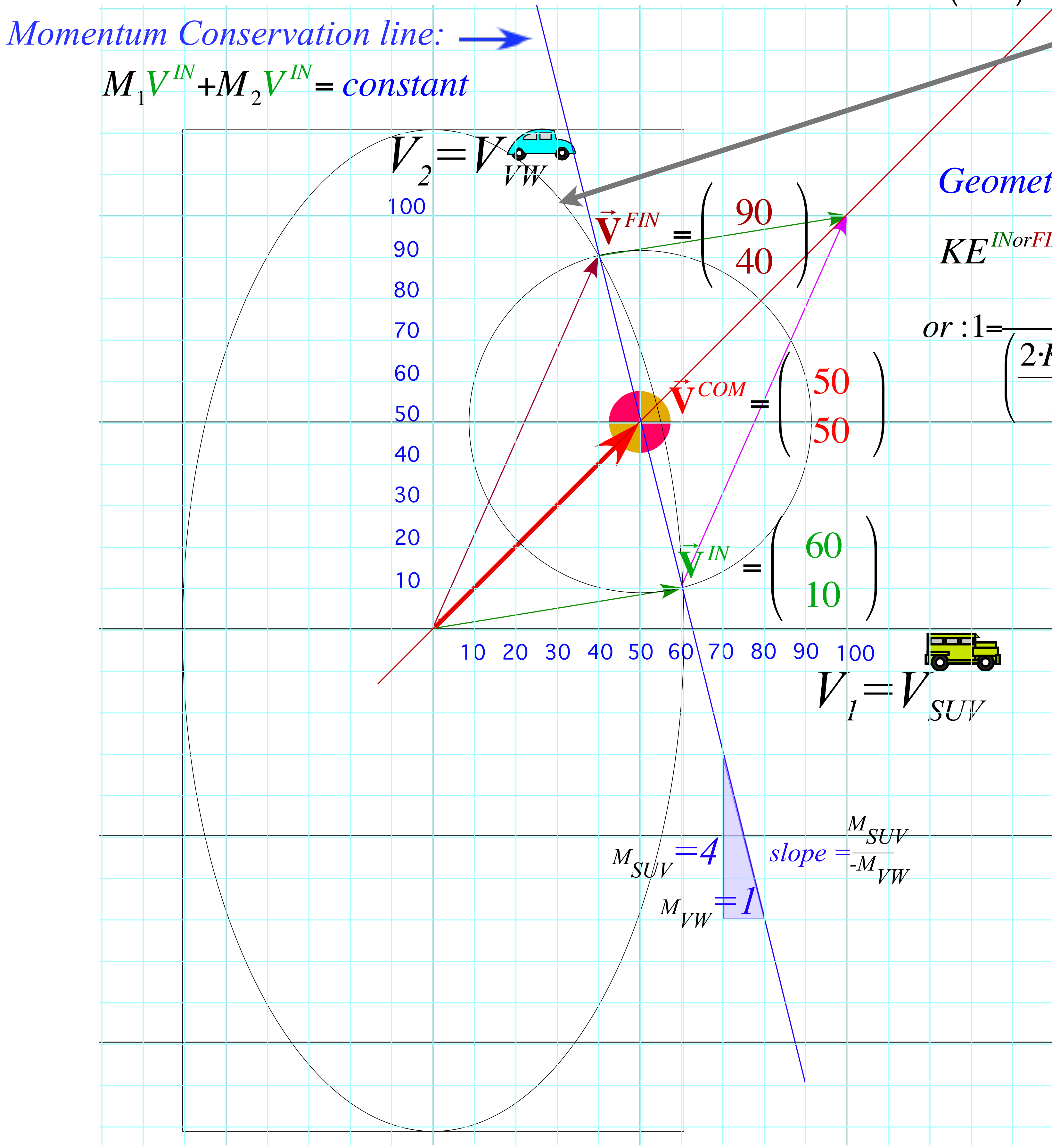

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Has the algebraic form: $1=\frac{x^2}{a^2}+\frac{y^2}{b^2}$

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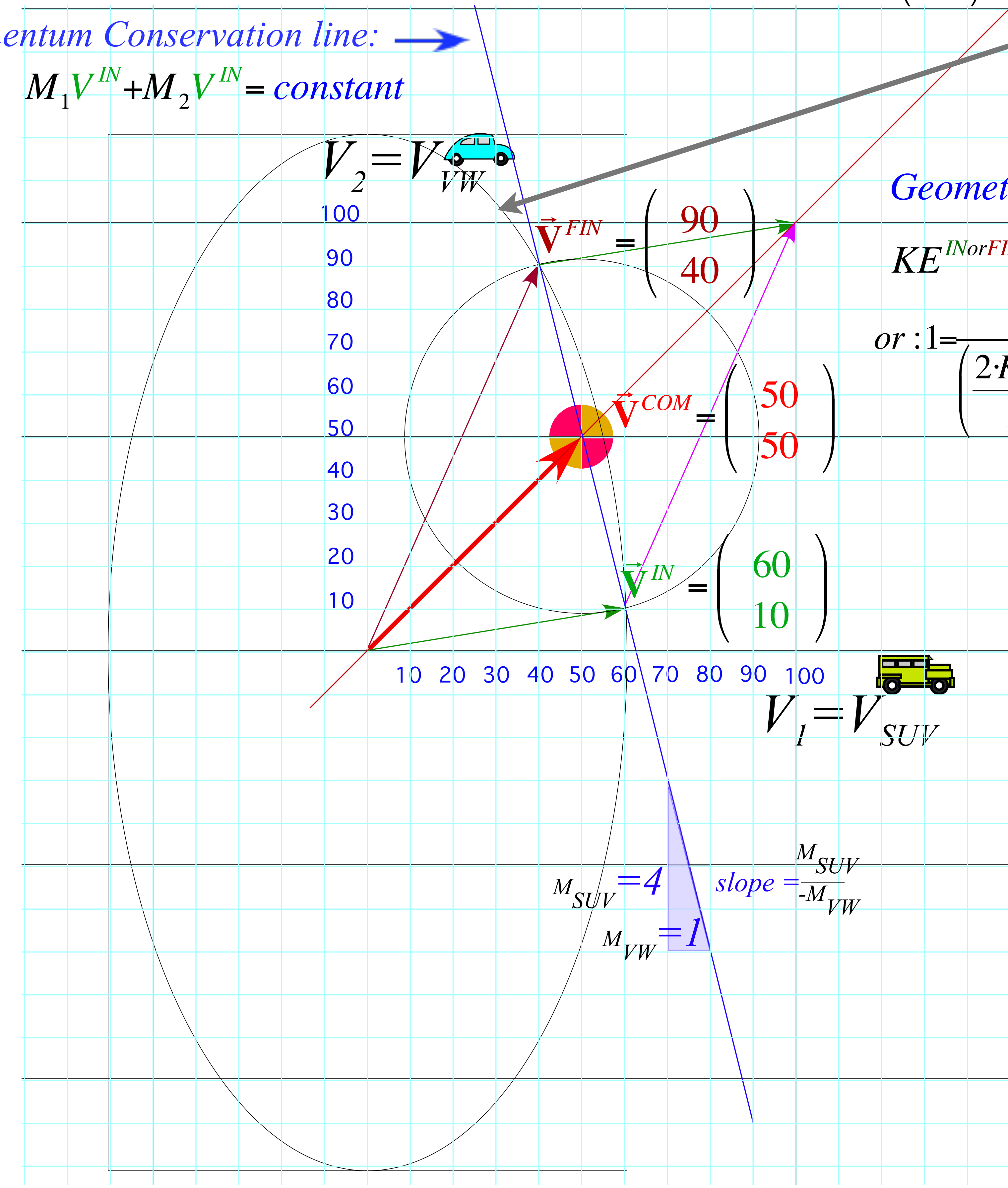


Geometry of KE Conservation **Theorem - 1**

$$KE^{INorFIN}=\tfrac{1}{2}M_1\left(V_1\right)^2+\tfrac{1}{2}M_2\left(V_2\right)^2=\tfrac{1}{2}4(60)^2+\tfrac{1}{2}1(10)^2=7{,}250$$

$$or: 1=\frac{V_1^2}{\left(\frac{2\cdot KE^{IFN}}{M_1}\right)}+\frac{V_2^2}{\left(\frac{2\cdot KE^{IFN}}{M_2}\right)}=\frac{V_1^2}{\left(\sqrt{\frac{2\cdot KE^{IFN}}{M_1}}\right)^2}+\frac{V_2^2}{\left(\sqrt{\frac{2\cdot KE^{IFN}}{M_2}}\right)^2}$$

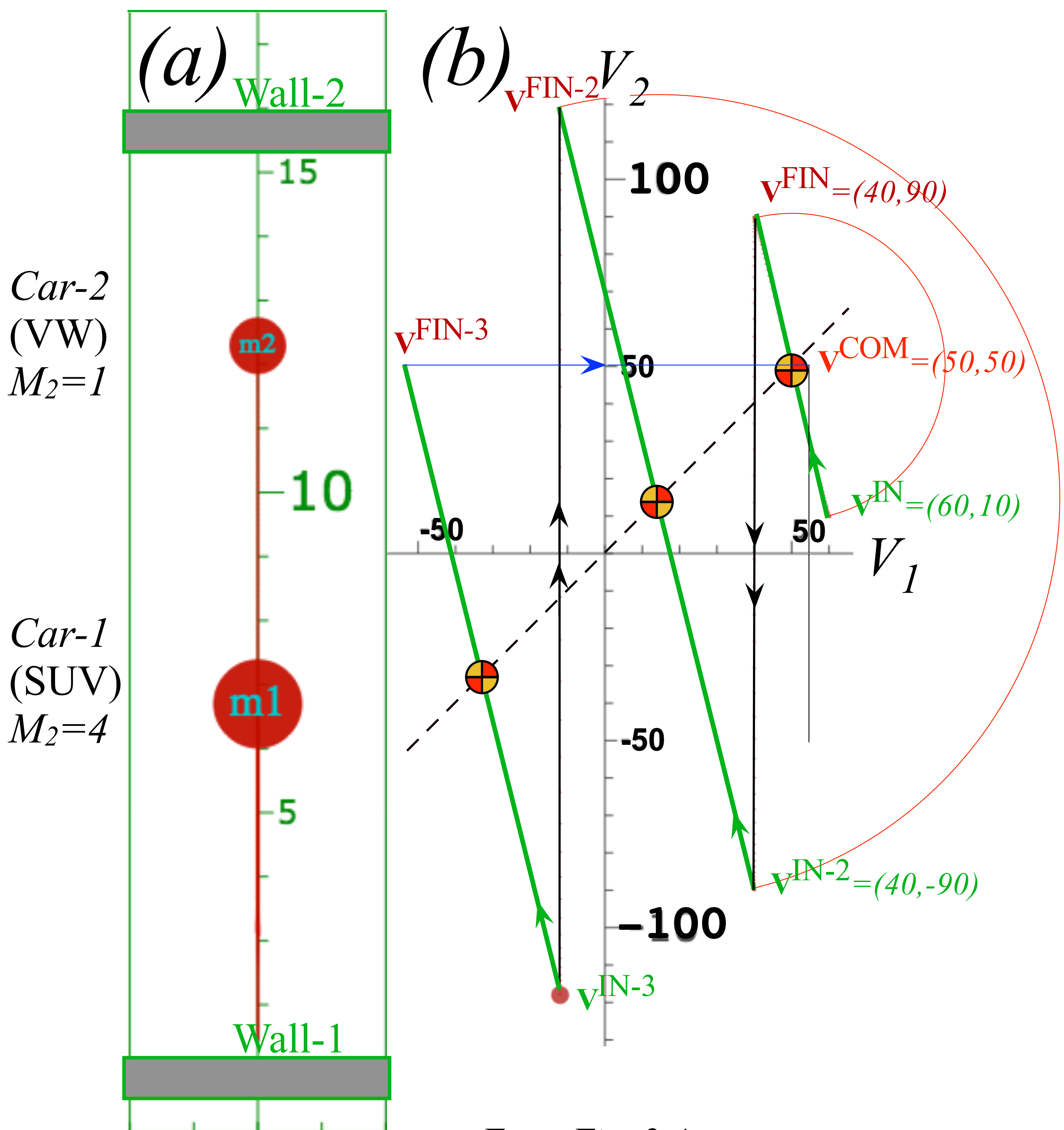
Has the algebraic form: $1=\frac{x^2}{a^2}+\frac{y^2}{b^2}$

$$elliptic\ radii: a=\sqrt{\frac{2KE^{INorFIN}}{M_1}} \quad b=\sqrt{\frac{2KE^{INorFIN}}{M_2}}$$

$$=\sqrt{\frac{2\cdot 7{,}250}{4}} \quad =\sqrt{\frac{2\cdot 7{,}250}{1}}$$

$$=60.21 \quad =120.42$$

BounceIt Simulation: frictionless 1D-track with elastic bumper cars bouncing between walls



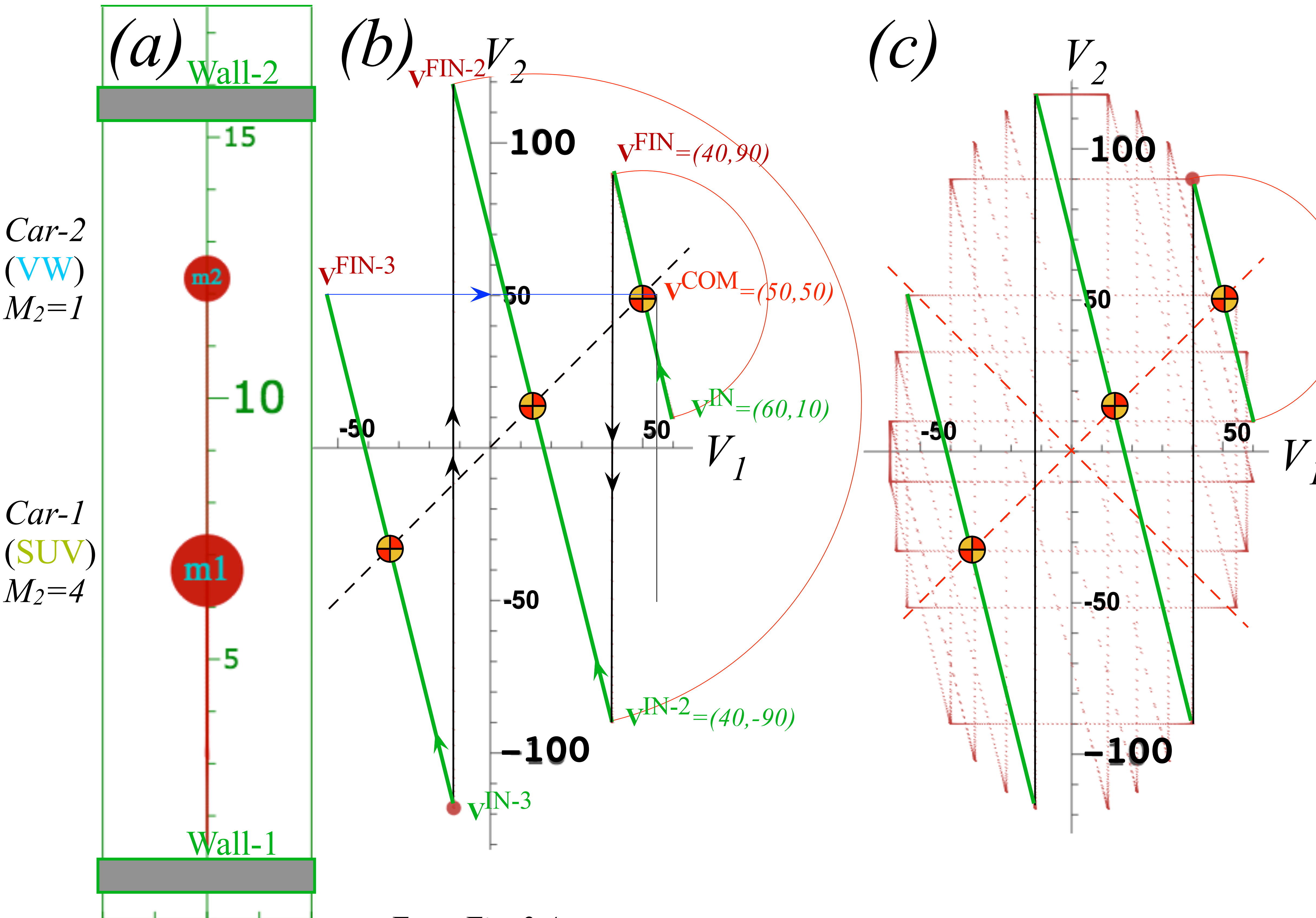
From Fig. 2.4

BounceIt
Superball Web Simulator
***Repeated** elastic Collisions*
Dual Panel
Space vs Space
and
V(VW) vs. V(SUV)

***Collision** Web Simulator*
***Basic** elastic Collision*
Dual Panel
Space vs Space
and
V(VW) vs. V(SUV)

BounceIt
Superball Web Simulator
***Basic** elastic Collision*
Dual Panel
Space vs Space
and
V(VW) vs. V(SUV)

BounceIt Simulation: frictionless 1D-track with elastic bumper cars bouncing between walls



From Fig. 2.4

Transpose symmetry ($M_{jk} = M_{kj}$) of the **M**-matrix implies: $\overleftarrow{\mathbf{V}}^{FIN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{IN} = \overleftarrow{\mathbf{V}}^{IN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{FIN}$

$$\begin{pmatrix} 40 & 90 \end{pmatrix} \bullet \begin{pmatrix} 4 & 0 \\ 0 & 1 \end{pmatrix} \bullet \begin{pmatrix} 60 \\ 10 \end{pmatrix} = \begin{pmatrix} 60 & 10 \end{pmatrix} \bullet \begin{pmatrix} 4 & 0 \\ 0 & 1 \end{pmatrix} \bullet \begin{pmatrix} 40 \\ 90 \end{pmatrix}$$

$$= 100 \cdot 105 = 100 \cdot 105 = 10{,}500$$

With ($M_{12} = 0 = M_{21}$) kinetic energy $KE^{INorFIN} = \frac{1}{2} \overleftarrow{\mathbf{V}} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}$ is the same at $\mathbf{V}=\mathbf{V}^{IN}$ and $\mathbf{V}=\mathbf{V}^{FIN}$.

$$V^{COM} P_{Total} - \frac{\overleftarrow{\mathbf{V}}^{FIN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{IN}}{2} = \frac{\overleftarrow{\mathbf{V}}^{IN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{IN}}{2} = \frac{\overleftarrow{\mathbf{V}}^{FIN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{FIN}}{2} = KE^{INorFIN}$$

$$12{,}500 - \frac{10{,}500}{2} = \frac{\begin{pmatrix} 60 & 10 \end{pmatrix} \bullet \begin{pmatrix} 4 & 0 \\ 0 & 1 \end{pmatrix} \bullet \begin{pmatrix} 60 \\ 10 \end{pmatrix}}{2} = \frac{\begin{pmatrix} 40 & 90 \end{pmatrix} \bullet \begin{pmatrix} 4 & 0 \\ 0 & 1 \end{pmatrix} \bullet \begin{pmatrix} 40 \\ 90 \end{pmatrix}}{2} = KE^{INorFIN}$$

$$12{,}500 - 5{,}250 = 7{,}250 = 7{,}250$$

Transpose symmetry ($M_{jk} = M_{kj}$) of the **M**-matrix implies: $\vec{\mathbf{V}}^{FIN} \bullet \vec{\mathbf{M}} \bullet \vec{\mathbf{V}}^{IN} = \vec{\mathbf{V}}^{IN} \bullet \vec{\mathbf{M}} \bullet \vec{\mathbf{V}}^{FIN}$

$$\begin{pmatrix} 40 & 90 \end{pmatrix} \bullet \begin{pmatrix} 4 & 0 \\ 0 & 1 \end{pmatrix} \bullet \begin{pmatrix} 60 \\ 10 \end{pmatrix} = \begin{pmatrix} 60 & 10 \end{pmatrix} \bullet \begin{pmatrix} 4 & 0 \\ 0 & 1 \end{pmatrix} \bullet \begin{pmatrix} 40 \\ 90 \end{pmatrix}$$

$$= 100 \cdot 105 = 100 \cdot 105 = 10{,}500$$

With ($M_{12} = 0 = M_{21}$) kinetic energy $KE^{INorFIN} = \frac{1}{2} \vec{\mathbf{V}} \bullet \vec{\mathbf{M}} \bullet \vec{\mathbf{V}}$ is the same at $\mathbf{V} = \mathbf{V}^{\mathrm{IN}}$ and $\mathbf{V} = \mathbf{V}^{\mathrm{FIN}}$.

$$V^{COM} P_{Total} - \frac{\vec{\mathbf{V}}^{FIN} \bullet \vec{\mathbf{M}} \bullet \vec{\mathbf{V}}^{IN}}{2} = \frac{\vec{\mathbf{V}}^{IN} \bullet \vec{\mathbf{M}} \bullet \vec{\mathbf{V}}^{IN}}{2} = \frac{\vec{\mathbf{V}}^{FIN} \bullet \vec{\mathbf{M}} \bullet \vec{\mathbf{V}}^{FIN}}{2} = KE^{INorFIN}$$

$$12{,}500 - \frac{10{,}500}{2} = \frac{\begin{pmatrix} 60 & 10 \end{pmatrix} \bullet \begin{pmatrix} 4 & 0 \\ 0 & 1 \end{pmatrix} \bullet \begin{pmatrix} 60 \\ 10 \end{pmatrix}}{2} = \frac{\begin{pmatrix} 40 & 90 \end{pmatrix} \bullet \begin{pmatrix} 4 & 0 \\ 0 & 1 \end{pmatrix} \bullet \begin{pmatrix} 40 \\ 90 \end{pmatrix}}{2} = KE^{INorFIN}$$

$$12{,}500 - 5{,}250 = 7{,}250 = 7{,}250$$

Consider kinetic energy KE^{COM} when $\mathbf{V} = \mathbf{V}^{\mathrm{COM}}$. It is reduced by *1,000* from 7,250 to 6,250.

$$KE^{COM} = \tfrac{1}{2} \vec{\mathbf{V}}^{COM} \bullet \vec{\mathbf{M}} \bullet \vec{\mathbf{V}}^{COM} = \tfrac{1}{2} \begin{pmatrix} 50 & 50 \end{pmatrix} \bullet \begin{pmatrix} 4 & 0 \\ 0 & 1 \end{pmatrix} \bullet \begin{pmatrix} 50 \\ 50 \end{pmatrix}$$

$$= \tfrac{1}{2}(50 \cdot 4 \cdot 50 + 50 \cdot 1 \cdot 50) = 2 \cdot 2500 + \tfrac{1}{2} \cdot 2500$$

$$= 5000 + \tfrac{1}{2} \cdot 1250 = 6{,}250$$

Geometry of Momentum Conservation **Axiom - 1**

$$(M_1+M_2)V^{COM}=M_1V_1^{IN}+M_2V_2^{IN}=M_1V_1^{FIN}+M_2V_2^{FIN}$$

Geometry of Kinetic Energy Conservation **Axiom-2/Theorem-1**

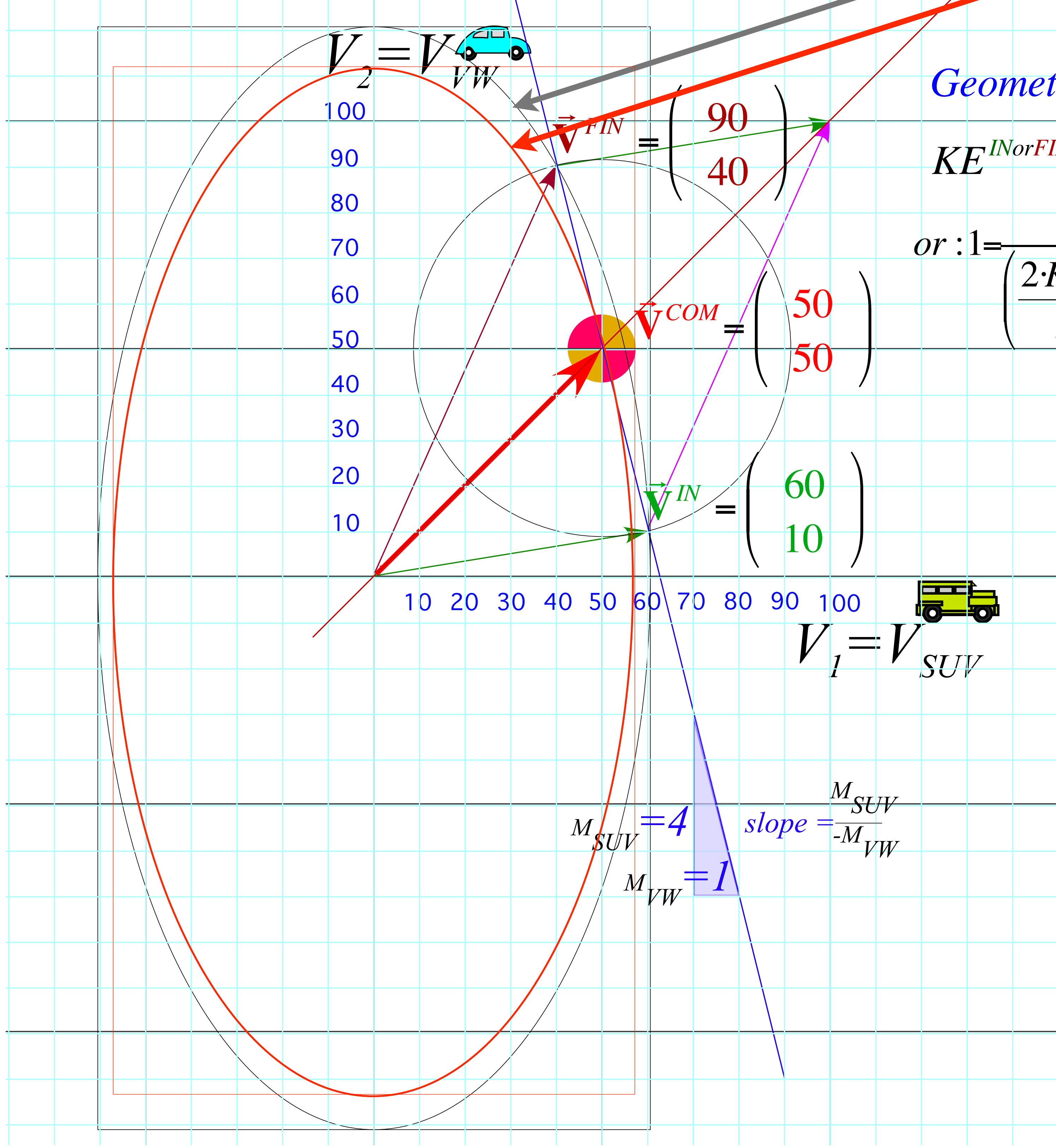
$$KE^{IN}=\tfrac{1}{2}M_1\left(V_1^{IN}\right)^2+\tfrac{1}{2}M_2\left(V_2^{IN}\right)^2=\tfrac{1}{2}M_1\left(V_1^{FIN}\right)^2+\tfrac{1}{2}M_2\left(V_2^{FIN}\right)^2=KE^{FIN}$$

Momentum Conservation line:

$M_1V^{IN}+M_2V^{IN}=$ *constant*

$KE^{INorFIN}$ *Conservation ellipse:*

KE^{COM} *Ka-runch ellipse:*



Geometry of KE Conservation **Theorem - 1**

$$KE^{INorFIN}=\tfrac{1}{2}M_1\left(V_1\right)^2+\tfrac{1}{2}M_2\left(V_2\right)^2$$

$$or:1=\frac{V_1^2}{\left(\frac{2\cdot KE^{IFN}}{M_1}\right)}+\frac{V_2^2}{\left(\frac{2\cdot KE^{IFN}}{M_2}\right)}=\frac{V_1^2}{\left(\sqrt{\frac{2\cdot KE^{IFN}}{M_1}}\right)^2}+\frac{V_2^2}{\left(\sqrt{\frac{2\cdot KE^{IFN}}{M_2}}\right)^2}$$

Has the algebraic form: $1=\frac{x^2}{a^2}+\frac{y^2}{b^2}$

Geometry of KE^{COM} *at CenterOfMomentum*

$$KE^{COM}=\tfrac{1}{2}M_1\left(V_1^{COM}\right)^2+\tfrac{1}{2}M_2\left(V_2^{COM}\right)^2$$

$$=\tfrac{1}{2}\left(M_1+M_2\right)\left(V^{COM}\right)^2$$

elliptic radii: $a^{COM}=\sqrt{\frac{KE^{COM}}{M_1}}$ $\quad b^{COM}=\sqrt{\frac{KE^{COM}}{M_2}}$

$=\sqrt{\frac{2\cdot 6{,}250}{4}}$ $\quad =\sqrt{\frac{2\cdot 6{,}250}{1}}$

$=55.90$ $\quad =111.80$

Transpose symmetry ($M_{jk} = M_{kj}$) of the **M**-matrix implies: $\overleftarrow{\mathbf{V}}^{FIN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{IN} = \overleftarrow{\mathbf{V}}^{IN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{FIN}$

$$\begin{pmatrix} 40 & 90 \end{pmatrix} \cdot \begin{pmatrix} 4 & 0 \\ 0 & 1 \end{pmatrix} \cdot \begin{pmatrix} 60 \\ 10 \end{pmatrix} = \begin{pmatrix} 60 & 10 \end{pmatrix} \cdot \begin{pmatrix} 4 & 0 \\ 0 & 1 \end{pmatrix} \cdot \begin{pmatrix} 40 \\ 90 \end{pmatrix}$$

$$= 100 \cdot 105 = 100 \cdot 105 = 10{,}500$$

With ($M_{12} = 0 = M_{21}$) kinetic energy $KE^{INorFIN} = \frac{1}{2} \overleftarrow{\mathbf{V}} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}$ is the same at $\mathbf{V} = \mathbf{V}^{IN}$ and $\mathbf{V} = \mathbf{V}^{FIN}$.

$$V^{COM} P_{Total} - \frac{\overleftarrow{\mathbf{V}}^{FIN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{IN}}{2} = \frac{\overleftarrow{\mathbf{V}}^{IN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{IN}}{2} = \frac{\overleftarrow{\mathbf{V}}^{FIN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{FIN}}{2} = KE^{INorFIN}$$

$$12{,}500 - \frac{10{,}500}{2} = \frac{\begin{pmatrix} 60 & 10 \end{pmatrix} \cdot \begin{pmatrix} 4 & 0 \\ 0 & 1 \end{pmatrix} \cdot \begin{pmatrix} 60 \\ 10 \end{pmatrix}}{2} = \frac{\begin{pmatrix} 40 & 90 \end{pmatrix} \cdot \begin{pmatrix} 4 & 0 \\ 0 & 1 \end{pmatrix} \cdot \begin{pmatrix} 40 \\ 90 \end{pmatrix}}{2} = KE^{INorFIN}$$

$$12{,}500 - 5{,}250 = 7{,}250 = 7{,}250$$

Consider kinetic energy KE^{COM} when $\mathbf{V} = \mathbf{V}^{COM}$. It is reduced by *1,000* from 7,250 to 6,250.

$$KE^{COM} = V^{COM} P_{Total} - \frac{\overleftarrow{\mathbf{V}}^{COM} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{COM}}{2} = \frac{1}{2} V^{COM} P_{Total} = \frac{\overleftarrow{\mathbf{V}}^{COM} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{COM}}{2} = \frac{\overleftarrow{\mathbf{V}}^{IN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{IN}}{4} + \frac{\overleftarrow{\mathbf{V}}^{FIN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{IN}}{4} = \frac{1}{2} KE^{INorFIN} + \frac{\overleftarrow{\mathbf{V}}^{FIN} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{IN}}{4}$$

$$12{,}500 - \frac{12{,}500}{2} = 6{,}250 = 6{,}250 = 3{,}625 + 2{,}625 = 3{,}625 + 2{,}625$$

$$KE^{COM} = \frac{1}{2} \overleftarrow{\mathbf{V}}^{COM} \bullet \overleftrightarrow{\mathbf{M}} \bullet \vec{\mathbf{V}}^{COM} = \frac{1}{2} \begin{pmatrix} 50 & 50 \end{pmatrix} \cdot \begin{pmatrix} 4 & 0 \\ 0 & 1 \end{pmatrix} \cdot \begin{pmatrix} 50 \\ 50 \end{pmatrix}$$

$$= \tfrac{1}{2}(50 \cdot 4 \cdot 50 + 50 \cdot 1 \cdot 50) = 2 \cdot 2500 + \tfrac{1}{2} \cdot 2500$$

$$= 5000 + \tfrac{1}{2} \cdot 1250 = 6{,}250$$

Transpose symmetry ($M_{jk} = M_{kj}$) of the **M**-matrix implies: $\vec{V}^{FIN} \bullet \overleftrightarrow{M} \bullet \vec{V}^{IN} = \vec{V}^{IN} \bullet \overleftrightarrow{M} \bullet \vec{V}^{FIN}$

$$\begin{pmatrix} 40 & 90 \end{pmatrix} \bullet \begin{pmatrix} 4 & 0 \\ 0 & 1 \end{pmatrix} \bullet \begin{pmatrix} 60 \\ 10 \end{pmatrix} = \begin{pmatrix} 60 & 10 \end{pmatrix} \bullet \begin{pmatrix} 4 & 0 \\ 0 & 1 \end{pmatrix} \bullet \begin{pmatrix} 40 \\ 90 \end{pmatrix}$$

$$= 100 \cdot 105 = 100 \cdot 105 = 10{,}500$$

With ($M_{12} = 0 = M_{21}$) kinetic energy $KE^{INorFIN} = \frac{1}{2} \vec{V} \bullet \overleftrightarrow{M} \bullet \vec{V}$ is the same at $\mathbf{V} = \mathbf{V}^{IN}$ and $\mathbf{V} = \mathbf{V}^{FIN}$.

$$V^{COM} P_{Total} - \frac{\vec{V}^{FIN} \bullet \overleftrightarrow{M} \bullet \vec{V}^{IN}}{2} = \frac{\vec{V}^{IN} \bullet \overleftrightarrow{M} \bullet \vec{V}^{IN}}{2} = \frac{\vec{V}^{FIN} \bullet \overleftrightarrow{M} \bullet \vec{V}^{FIN}}{2} = KE^{INorFIN}$$

$$12{,}500 - \frac{10{,}500}{2} = \frac{\begin{pmatrix} 60 & 10 \end{pmatrix} \bullet \begin{pmatrix} 4 & 0 \\ 0 & 1 \end{pmatrix} \bullet \begin{pmatrix} 60 \\ 10 \end{pmatrix}}{2} = \frac{\begin{pmatrix} 40 & 90 \end{pmatrix} \bullet \begin{pmatrix} 4 & 0 \\ 0 & 1 \end{pmatrix} \bullet \begin{pmatrix} 40 \\ 90 \end{pmatrix}}{2} = KE^{INorFIN}$$

$$12{,}500 - 5{,}250 = 7{,}250 = 7{,}250$$

Consider kinetic energy KE^{COM} when $\mathbf{V} = \mathbf{V}^{COM}$. It is reduced by *1,000* from 7,250 to 6,250.

$$KE^{COM} = V^{COM} P_{Total} - \frac{\vec{V}^{COM} \bullet \overleftrightarrow{M} \bullet \vec{V}^{COM}}{2} = \frac{1}{2} V^{COM} P_{Total} = \frac{\vec{V}^{COM} \bullet \overleftrightarrow{M} \bullet \vec{V}^{COM}}{2} = \frac{\vec{V}^{IN} \bullet \overleftrightarrow{M} \bullet \vec{V}^{IN}}{4} + \frac{\vec{V}^{FIN} \bullet \overleftrightarrow{M} \bullet \vec{V}^{IN}}{4} = \frac{1}{2} KE^{INorFIN} + \frac{\vec{V}^{FIN} \bullet \overleftrightarrow{M} \bullet \vec{V}^{IN}}{4}$$

$$12{,}500 - \frac{12{,}500}{2} = 6{,}250 = 6{,}250 = 3{,}625 + 2{,}625 = 3{,}625 + 2{,}625$$

$$KE^{COM} = \frac{1}{2} \vec{V}^{COM} \bullet \overleftrightarrow{M} \bullet \vec{V}^{COM} = \frac{1}{2} \begin{pmatrix} 50 & 50 \end{pmatrix} \bullet \begin{pmatrix} 4 & 0 \\ 0 & 1 \end{pmatrix} \bullet \begin{pmatrix} 50 \\ 50 \end{pmatrix}$$

$$= \tfrac{1}{2}(50 \cdot 4 \cdot 50 + 50 \cdot 1 \cdot 50) = 2 \cdot 2500 + \tfrac{1}{2} \cdot 2500$$

$$= 5000 + \tfrac{1}{2} \cdot 1250 = 6{,}250$$

Introducing *Potential Energy=PE*

Difference is inelastic "*ka-Runch*" $KE^{INorFIN} - KE^{COM}$. For elastic "*ka-Bong*" the *1,000* is PE^{COM} of compression.

$$KE^{INorFIN} - KE^{COM} = \frac{\vec{V}^{IN} \bullet \overleftrightarrow{M} \bullet \vec{V}^{IN}}{4} - \frac{\vec{V}^{FIN} \bullet \overleftrightarrow{M} \bullet \vec{V}^{IN}}{4}$$

$$1{,}000 = 3{,}625 - 2{,}625$$

Transpose symmetry ($M_{jk}=M_{kj}$) of the **M**-matrix implies: $\vec{V}^{FIN}\cdot\overleftrightarrow{M}\cdot\vec{V}^{IN} = \vec{V}^{IN}\cdot\overleftrightarrow{M}\cdot\vec{V}^{FIN}$

$$\begin{pmatrix}40 & 90\end{pmatrix}\cdot\begin{pmatrix}4 & 0\\0 & 1\end{pmatrix}\cdot\begin{pmatrix}60\\10\end{pmatrix}=\begin{pmatrix}60 & 10\end{pmatrix}\cdot\begin{pmatrix}4 & 0\\0 & 1\end{pmatrix}\cdot\begin{pmatrix}40\\90\end{pmatrix}$$

$$= 100\cdot105 = 100\cdot105 = 10{,}500$$

With ($M_{12}=0=M_{21}$) kinetic energy $KE^{INorFIN}=\frac{1}{2}\vec{V}\cdot\overleftrightarrow{M}\cdot\vec{V}$ is the same at $\mathbf{V}=\mathbf{V}^{IN}$ and $\mathbf{V}=\mathbf{V}^{FIN}$.

$$V^{COM}P_{Total}-\frac{\vec{V}^{FIN}\cdot\overleftrightarrow{M}\cdot\vec{V}^{IN}}{2}=\frac{\vec{V}^{IN}\cdot\overleftrightarrow{M}\cdot\vec{V}^{IN}}{2}=\frac{\vec{V}^{FIN}\cdot\overleftrightarrow{M}\cdot\vec{V}^{FIN}}{2}=KE^{INorFIN}$$

$$12{,}500-\frac{10{,}500}{2}=\frac{\begin{pmatrix}60 & 10\end{pmatrix}\cdot\begin{pmatrix}4 & 0\\0 & 1\end{pmatrix}\cdot\begin{pmatrix}60\\10\end{pmatrix}}{2}=\frac{\begin{pmatrix}40 & 90\end{pmatrix}\cdot\begin{pmatrix}4 & 0\\0 & 1\end{pmatrix}\cdot\begin{pmatrix}40\\90\end{pmatrix}}{2}=KE^{INorFIN}$$

$$12{,}500-5{,}250=7{,}250=7{,}250$$

Consider kinetic energy KE^{COM} when $\mathbf{V}=\mathbf{V}^{COM}$. It is reduced by *1,000* from 7,250 to 6,250.

$$KE^{COM}=V^{COM}P_{Total}-\frac{\vec{V}^{COM}\cdot\overleftrightarrow{M}\cdot\vec{V}^{COM}}{2}=\frac{1}{2}V^{COM}P_{Total}=\frac{\vec{V}^{COM}\cdot\overleftrightarrow{M}\cdot\vec{V}^{COM}}{2}=\frac{\vec{V}^{IN}\cdot\overleftrightarrow{M}\cdot\vec{V}^{IN}}{4}+\frac{\vec{V}^{FIN}\cdot\overleftrightarrow{M}\cdot\vec{V}^{IN}}{4}=\frac{1}{2}KE^{INorFIN}+\frac{\vec{V}^{FIN}\cdot\overleftrightarrow{M}\cdot\vec{V}^{IN}}{4}$$

$$12{,}500-\frac{12{,}500}{2}=6{,}250=6{,}250=3{,}625+2{,}625=3{,}625+2{,}625$$

$$KE^{COM}=\frac{1}{2}\vec{V}^{COM}\cdot\overleftrightarrow{M}\cdot\vec{V}^{COM}=\frac{1}{2}\begin{pmatrix}50 & 50\end{pmatrix}\cdot\begin{pmatrix}4 & 0\\0 & 1\end{pmatrix}\cdot\begin{pmatrix}50\\50\end{pmatrix}$$

$$=\frac{1}{2}(50\cdot4\cdot50+50\cdot1\cdot50)=2\cdot2500+\frac{1}{2}\cdot2500$$

$$=5000+\frac{1}{2}\cdot1250=6{,}250$$

Introducing
Potential Energy=PE

Difference is inelastic "*ka-Runch*" $KE^{INorFIN}$-KE^{COM}. For elastic "*ka-Bong*" the *1,000* is PE^{COM} of compression.

$$KE^{INorFIN}-KE^{COM}=\frac{\vec{V}^{IN}\cdot\overleftrightarrow{M}\cdot\vec{V}^{IN}}{4}-\frac{\vec{V}^{FIN}\cdot\overleftrightarrow{M}\cdot\vec{V}^{IN}}{4}$$

$$1{,}000=3{,}625-2{,}625$$

$$KE^{COM}=\frac{\vec{V}^{IN}\cdot\overleftrightarrow{M}\cdot\vec{V}^{IN}}{4}+\frac{\vec{V}^{FIN}\cdot\overleftrightarrow{M}\cdot\vec{V}^{IN}}{4}$$

$$6{,}250=3{,}625+2{,}625$$

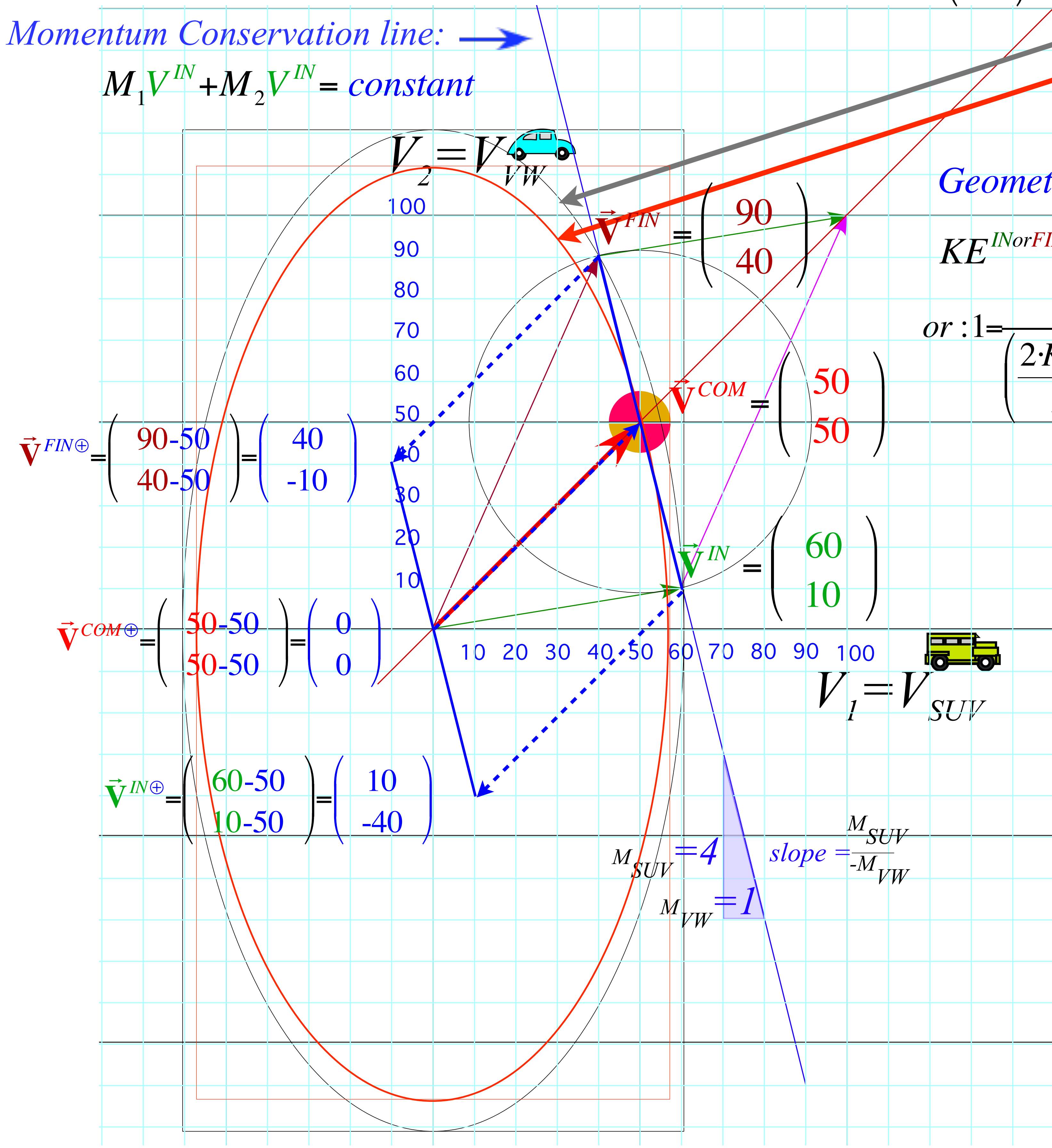
Difference $KE^{INorFIN}$-KE^{COM} = *1,000* is the same in *all* frames including *COM*-frame where $\mathbf{V}^{COM}=\mathbf{0}$.

Geometry of Momentum Conservation **Axiom - 1**

$$(M_1+M_2)V^{COM}=M_1V_1^{IN}+M_2V_2^{IN}=M_1V_1^{FIN}+M_2V_2^{FIN}$$

Geometry of Kinetic Energy Conservation **Axiom-2/Theorem-1**

$$KE^{IN}=\tfrac{1}{2}M_1\left(V_1^{IN}\right)^2+\tfrac{1}{2}M_2\left(V_2^{IN}\right)^2=\tfrac{1}{2}M_1\left(V_1^{FIN}\right)^2+\tfrac{1}{2}M_2\left(V_2^{FIN}\right)^2=KE^{FIN}$$



$KE^{INorFIN}$ *Conservation ellipse:*

KE^{COM} *Ka-runch ellipse:*

Geometry of KE Conservation **Theorem - 1**

$$KE^{INorFIN}=\tfrac{1}{2}M_1\left(V_1\right)^2+\tfrac{1}{2}M_2\left(V_2\right)^2$$

$$or:1=\frac{V_1^2}{\left(\frac{2\cdot KE^{IFN}}{M_1}\right)}+\frac{V_2^2}{\left(\frac{2\cdot KE^{IFN}}{M_2}\right)}=\frac{V_1^2}{\left(\sqrt{\frac{2\cdot KE^{IFN}}{M_1}}\right)^2}+\frac{V_2^2}{\left(\sqrt{\frac{2\cdot KE^{IFN}}{M_2}}\right)^2}$$

Has the algebraic form: $1=\frac{x^2}{a^2}+\frac{y^2}{b^2}$

Geometry of KE^{COM} *at CenterOfMomentum*

$$KE^{COM}=\tfrac{1}{2}M_1\left(V_1^{COM}\right)^2+\tfrac{1}{2}M_2\left(V_2^{COM}\right)^2$$

$$=\tfrac{1}{2}\left(M_1+M_2\right)\left(V^{COM}\right)^2$$

elliptic radii: $a^{COM}=\sqrt{\frac{KE^{COM}}{M_1}}$ $\quad b^{COM}=\sqrt{\frac{KE^{COM}}{M_2}}$

$=\sqrt{\frac{2\cdot 6{,}250}{4}}$ $\quad =\sqrt{\frac{2\cdot 6{,}250}{1}}$

$=55.90$ $\quad =111.80$

Geometry of Momentum Conservation **Axiom-1**

$$(M_1+M_2)V^{COM}=M_1V_1^{IN}+M_2V_2^{IN}=M_1V_1^{FIN}+M_2V_2^{FIN}$$

Geometry of Kinetic Energy Conservation **Axiom-2/Theorem-1**

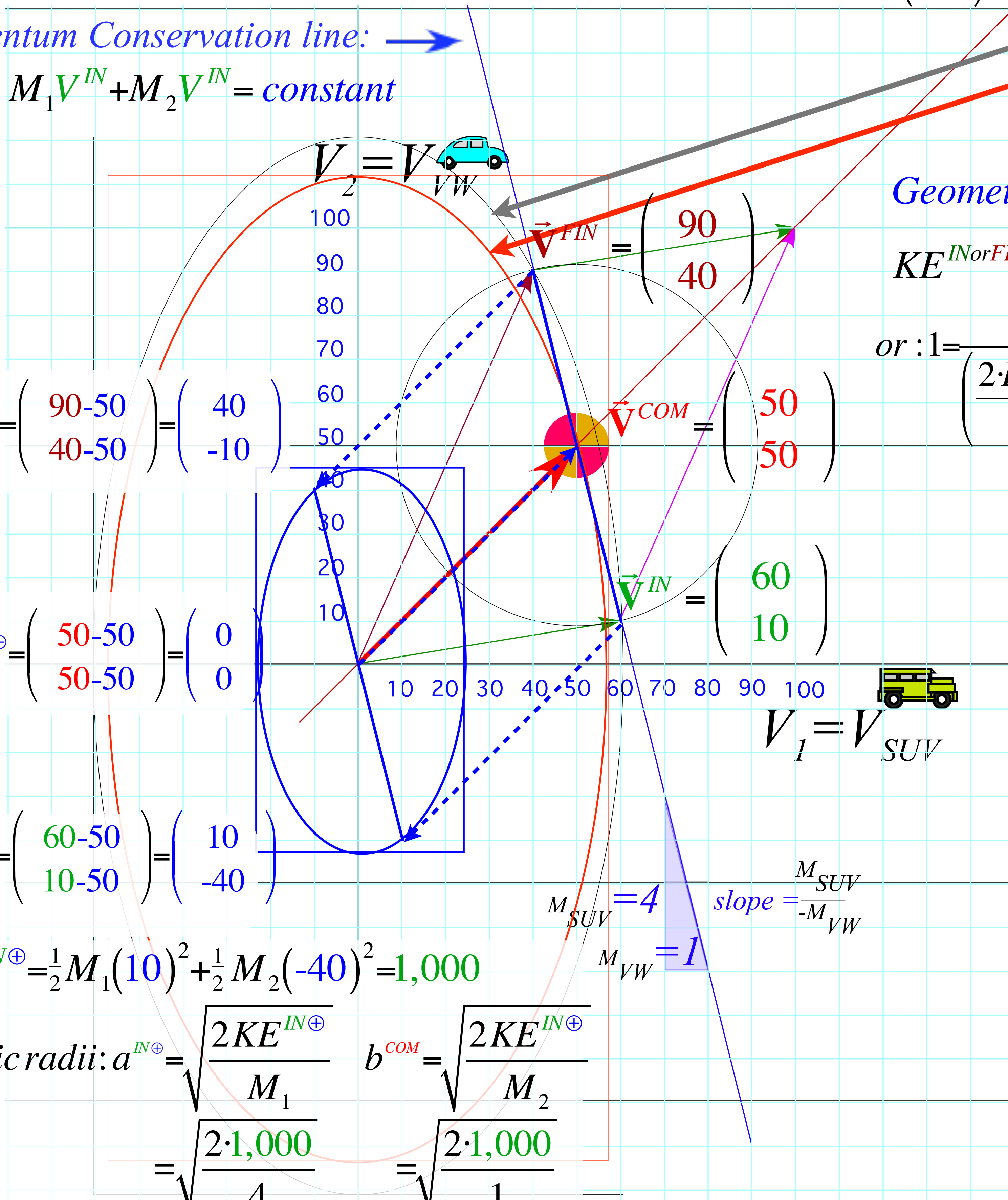
$$KE^{IN}=\tfrac{1}{2}M_1\left(V_1^{IN}\right)^2+\tfrac{1}{2}M_2\left(V_2^{IN}\right)^2=\tfrac{1}{2}M_1\left(V_1^{FIN}\right)^2+\tfrac{1}{2}M_2\left(V_2^{FIN}\right)^2=KE^{FIN}$$

Momentum Conservation line:

$$M_1V^{IN}+M_2V^{IN}=\textit{constant}$$

$KE^{INorFIN}$ *Conservation ellipse:*

KE^{COM} *Ka-runch ellipse:*



$$KE^{IN\oplus}=\tfrac{1}{2}M_1(10)^2+\tfrac{1}{2}M_2(-40)^2=1{,}000$$

$$\textit{elliptic radii}: a^{IN\oplus}=\sqrt{\frac{2KE^{IN\oplus}}{M_1}}=\sqrt{\frac{2\cdot 1{,}000}{4}}=22.36 \qquad b^{COM}=\sqrt{\frac{2KE^{IN\oplus}}{M_2}}=\sqrt{\frac{2\cdot 1{,}000}{1}}=44.72$$

Geometry of KE Conservation **Theorem-1**

$$KE^{INorFIN}=\tfrac{1}{2}M_1\left(V_1\right)^2+\tfrac{1}{2}M_2\left(V_2\right)^2$$

$$or: 1=\frac{V_1^2}{\left(\frac{2\cdot KE^{IFN}}{M_1}\right)}+\frac{V_2^2}{\left(\frac{2\cdot KE^{IFN}}{M_2}\right)}=\frac{V_1^2}{\left(\sqrt{\frac{2\cdot KE^{IFN}}{M_1}}\right)^2}+\frac{V_2^2}{\left(\sqrt{\frac{2\cdot KE^{IFN}}{M_2}}\right)^2}$$

Has the algebraic form: $1=\frac{x^2}{a^2}+\frac{y^2}{b^2}$

Geometry of KE^{COM} *at CenterOfMomentum*

$$KE^{COM}=\tfrac{1}{2}M_1\left(V_1^{COM}\right)^2+\tfrac{1}{2}M_2\left(V_2^{COM}\right)^2$$

$$=\tfrac{1}{2}\left(M_1+M_2\right)\left(V^{COM}\right)^2$$

$$\textit{elliptic radii}: a^{COM}=\sqrt{\frac{KE^{COM}}{M_1}}=\sqrt{\frac{2\cdot 6{,}250}{4}}=55.90 \qquad b^{COM}=\sqrt{\frac{KE^{COM}}{M_2}}=\sqrt{\frac{2\cdot 6{,}250}{1}}=111.80$$

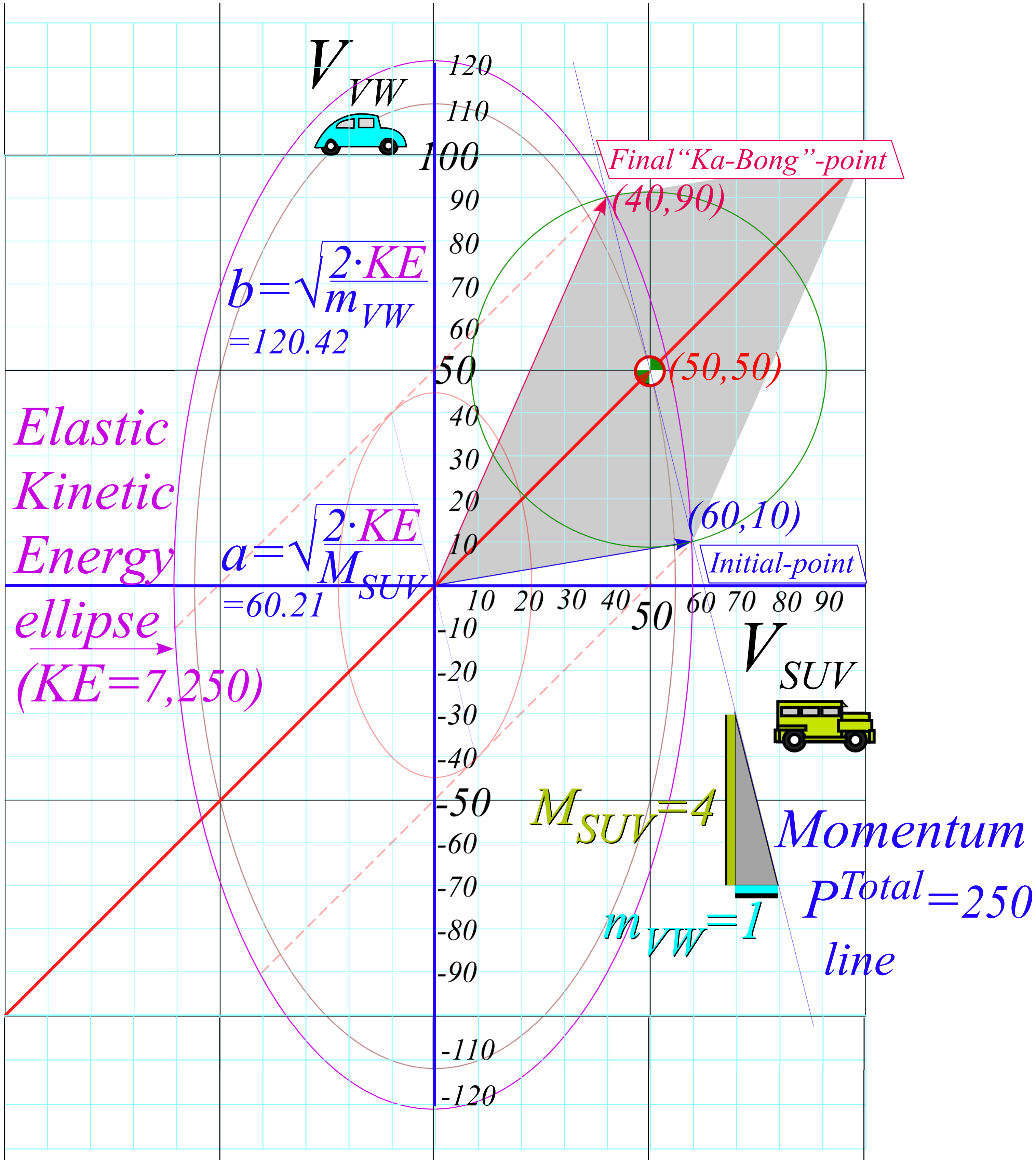


Fig. 3.1 a
in Unit 1

Developing
Conservation-of-Momentum
The key axiom of mechanics
leading to
Conservation-of-Energy Theorem

If and only if…
*there is **T-Symmetry***

Fig. 3.1

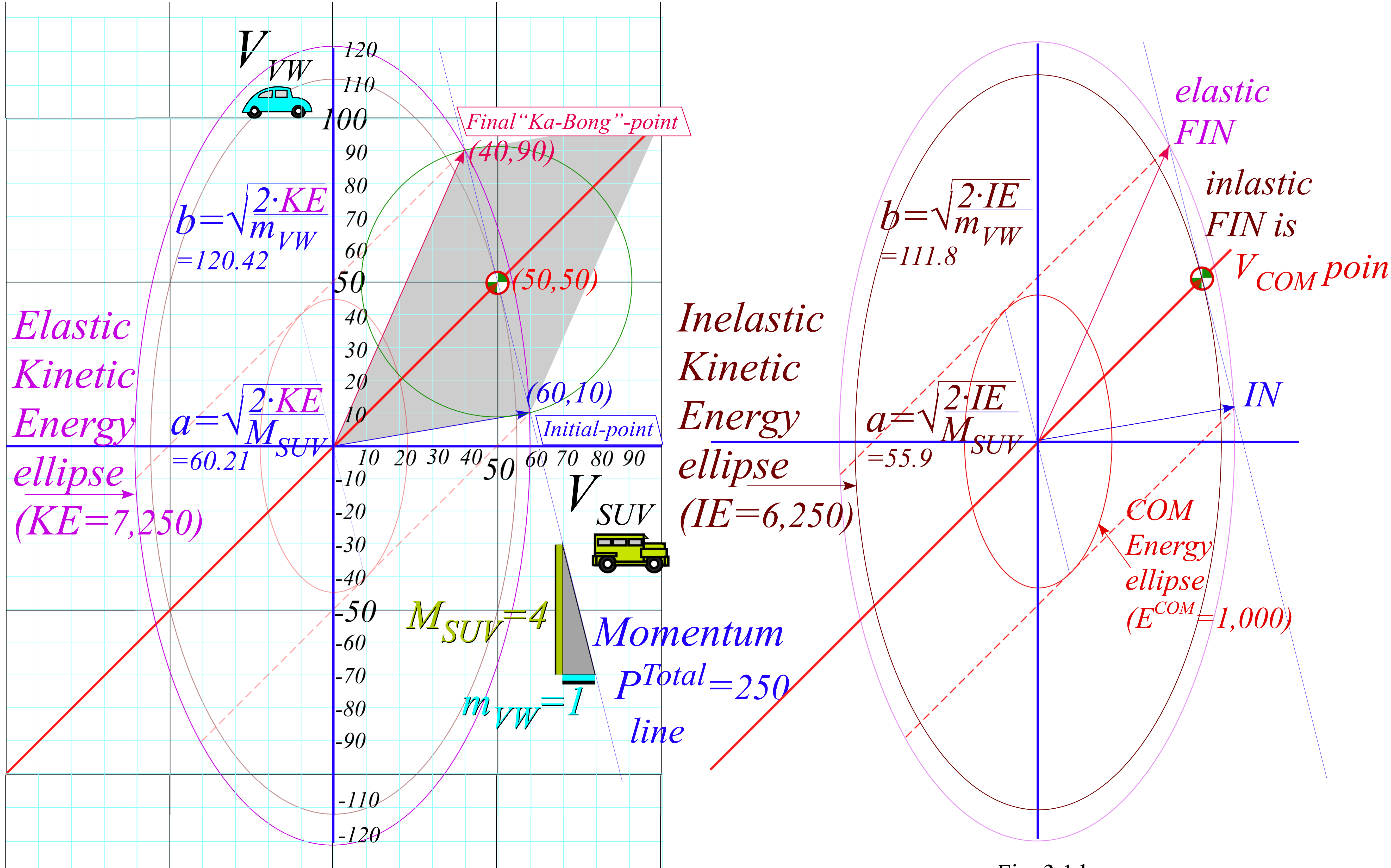


Fig. 3.1 a
in Unit 1

Fig. 3.1 b
in Unit 1

Fig. 3.1

As usual in physics, opposite extremes are easier to analyze than the generic "real(er) world" in between!

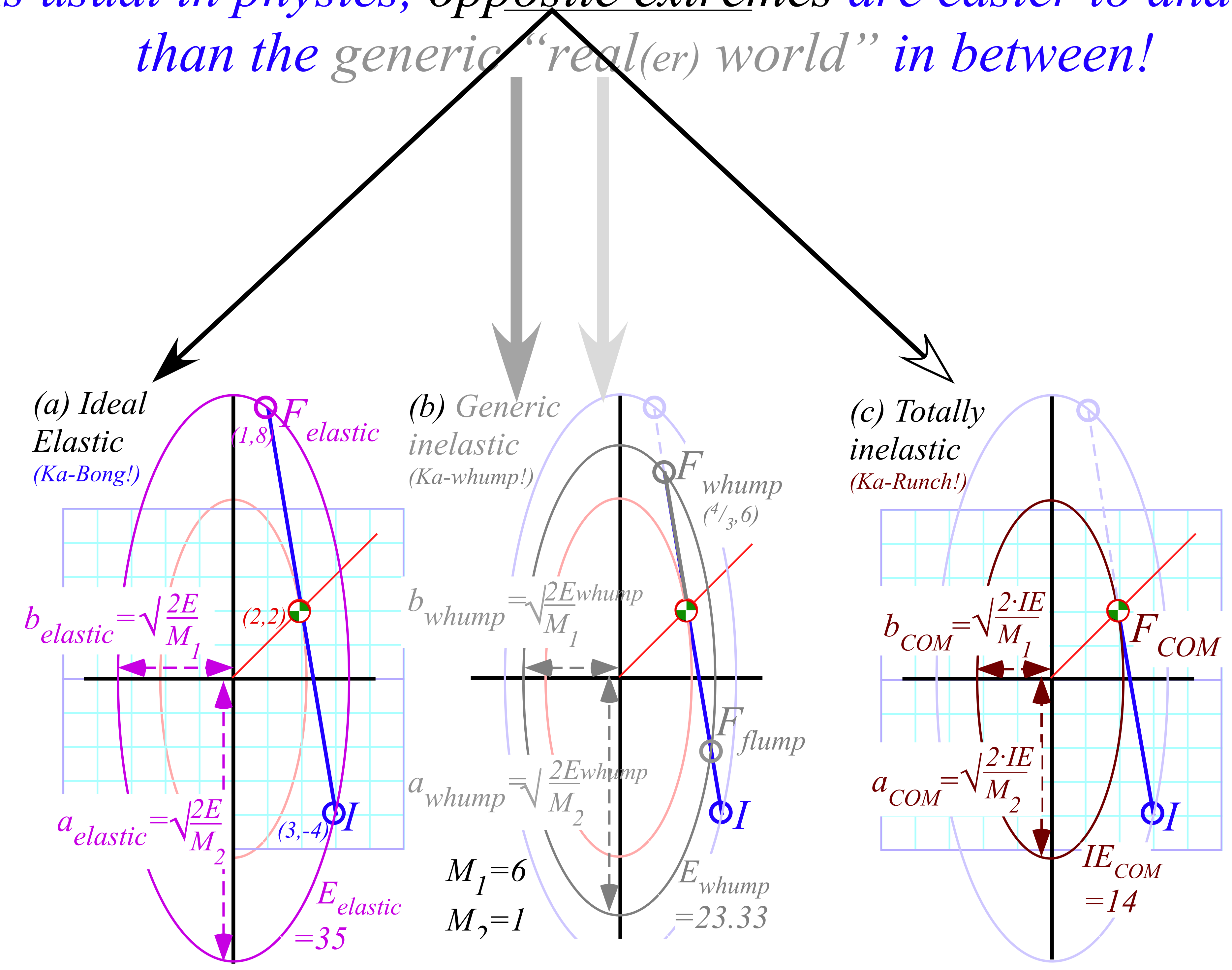


Fig. 2.3 (6-Ton SUV)

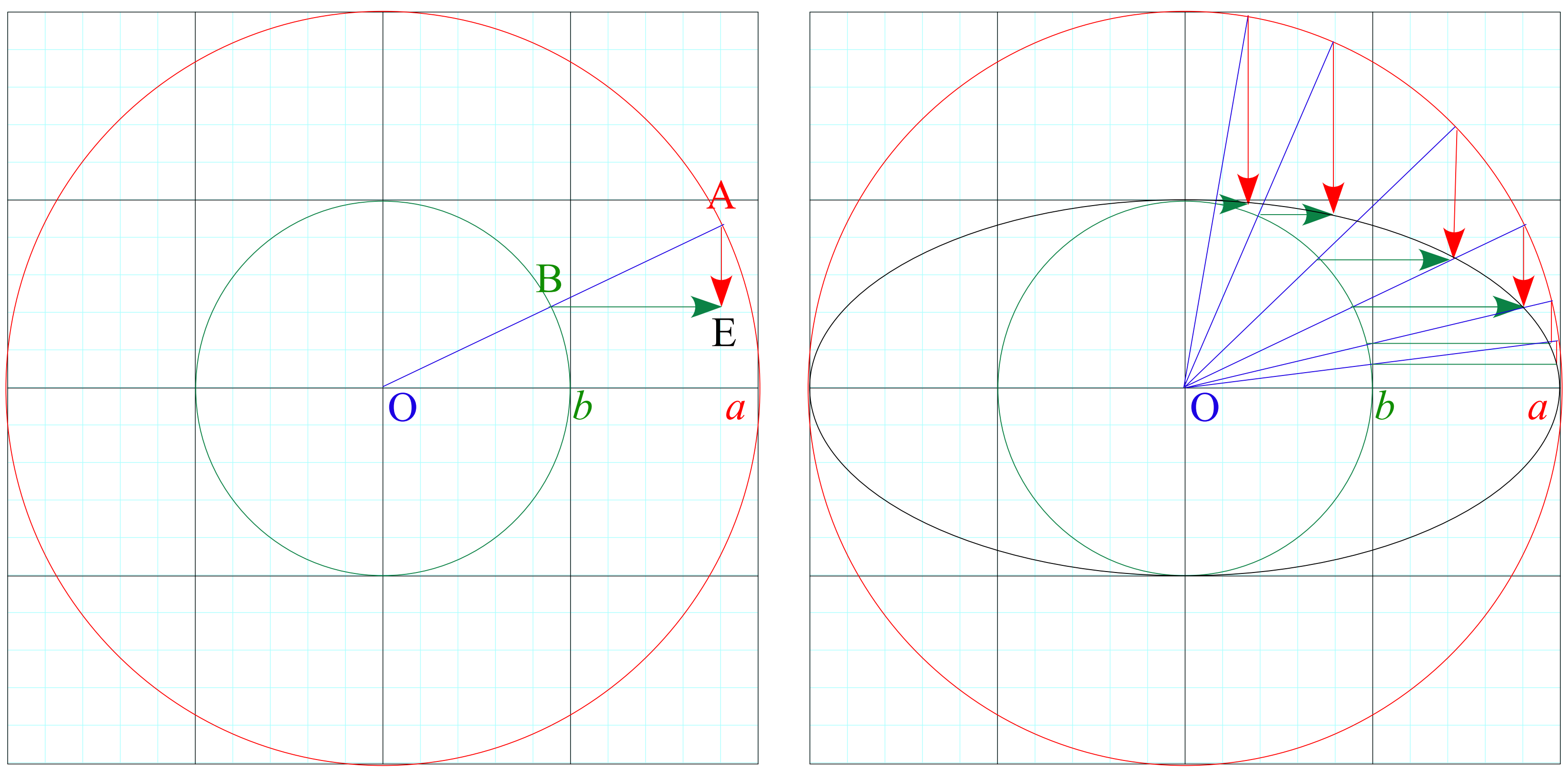
*(During Bush II era an SUV with a mass of at least **6 tons** allowed its owner to take a 100% write-off (up to $100,000) on Federal Income Tax.)*

Here **T-Symmetry** is best

Here **T-Symmetry** is less

Here **T-Symmetry** is least

Graph paper facilitates construction of energy ellipses given the two radii a and b in KE equation.
First step: draw concentric circles of radius a and b.
Then any radial line OBA “points” to point E on the ellipse.
Ellipse point E lies at the intersection of a vertical line AE thru radial intersection A with circle a and a horizontal line BE thru radial intersection B with circle b.
Graph grid helps locate E for a radius OBA, and usually there is no need to draw AE or BE.
You can pick x and find y or else *vice-versa*.



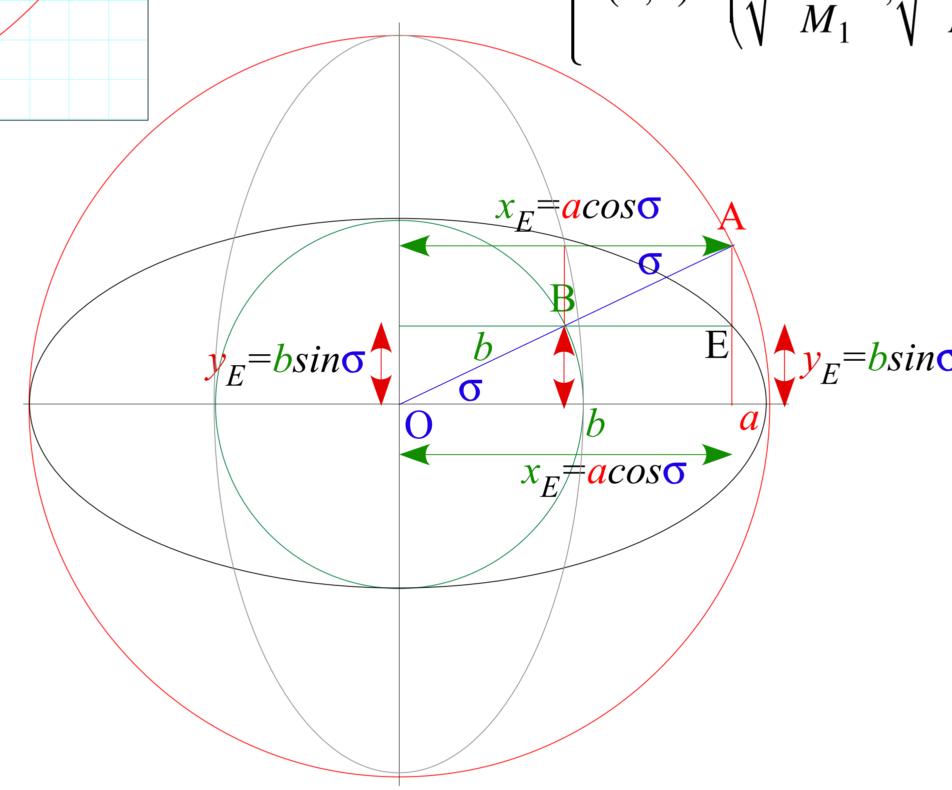
$$\frac{1}{2}M_1 \cdot V_1^2 + \frac{1}{2}M_2 \cdot V_2^2 = KE$$

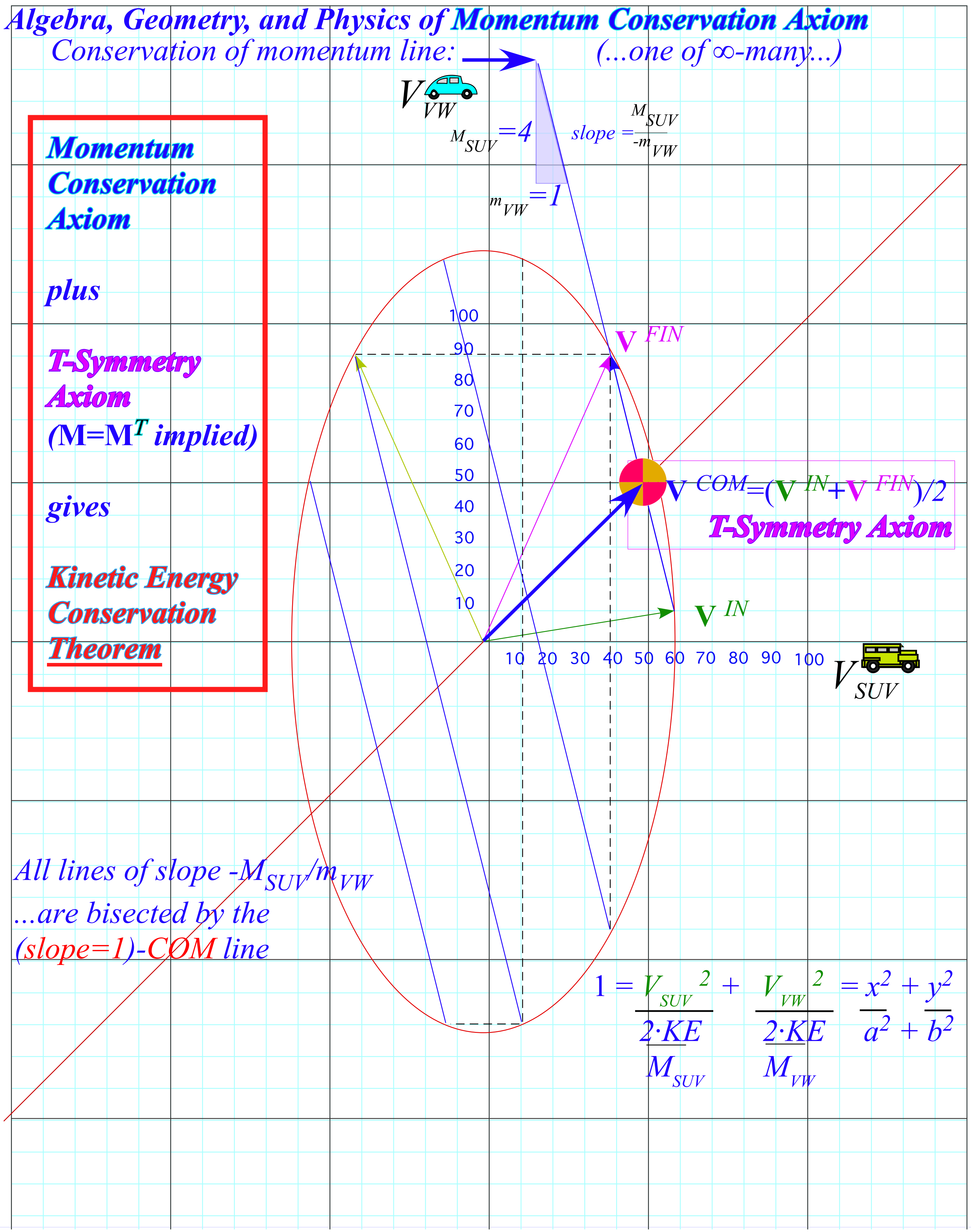
$$\frac{V_1^2}{\left(\frac{2 \cdot KE}{M_1}\right)} + \frac{V_2^2}{\left(\frac{2 \cdot KE}{M_2}\right)} = 1$$

$$\frac{x^2}{a^2} + \frac{y^2}{b^2} = 1$$

$$\begin{cases} (x,y) = (V_1, V_2) \\ (a,b) = \left(\sqrt{\frac{2 \cdot KE}{M_1}}, \sqrt{\frac{2 \cdot KE}{M_2}}\right) \end{cases}$$

Ellipse coordinates ($x_E = a \cdot \cos\sigma$, $y_E = b \cdot \sin\sigma$) are rescaled base and altitude
($x_r = r \cdot \cos\sigma$, $y_r = r \cdot \sin\sigma$) of Fig. 2.6.





Developing

Conservation-of-Momentum

The key axiom of mechanics

leading to

Conservation-of-Energy Theorem

If and only if…

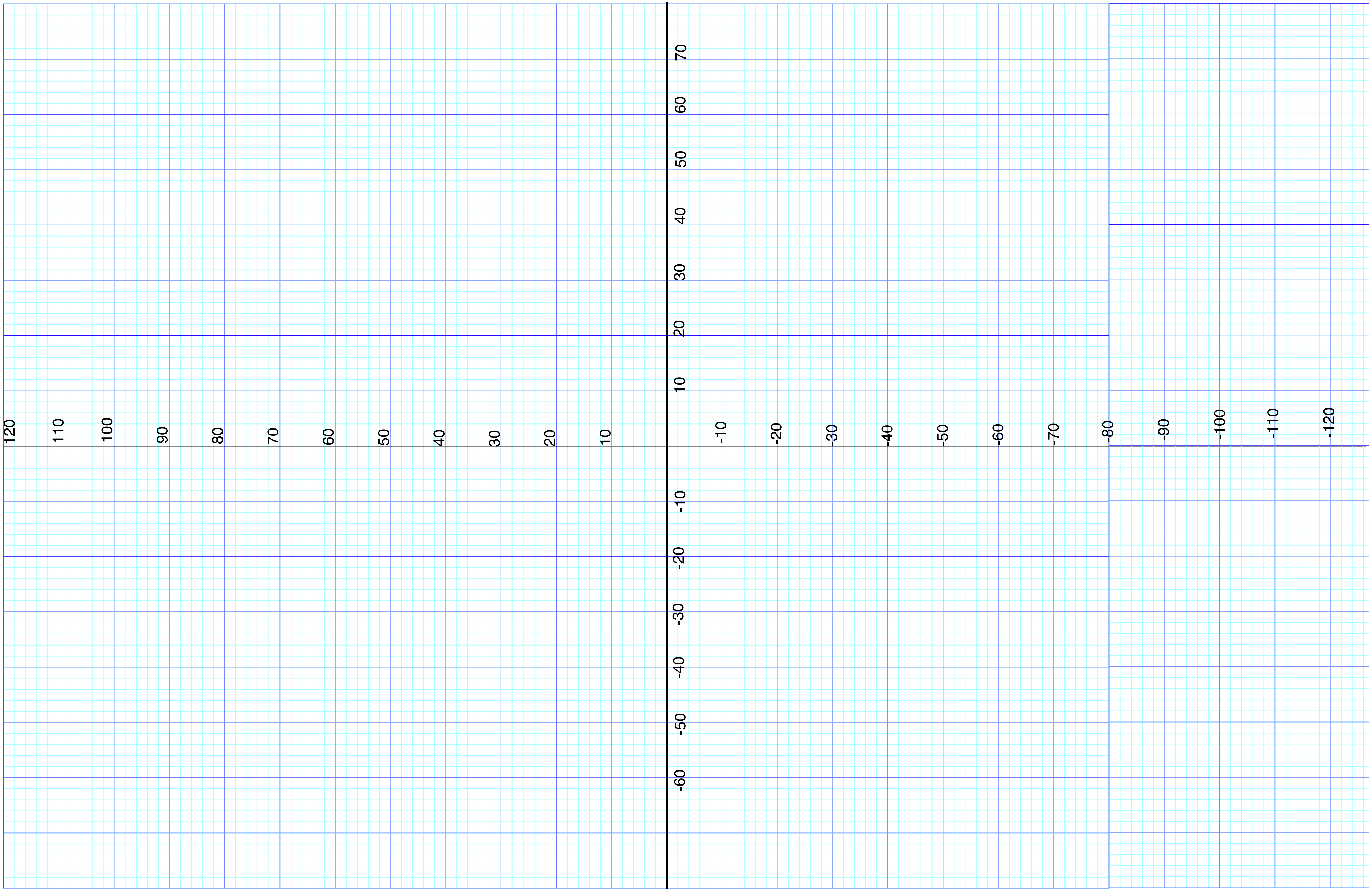
there is T-Symmetry

$V^{COM}\bullet M\bullet V^{COM} - 1/2\, V^{FIN}\bullet M\bullet V^{IN}$

$= 1/2\, V^{IN}\bullet M\bullet V^{IN} = 1/2\, V^{FIN}\bullet M\bullet V^{FIN}$

These are equations for energy conservation ellipse:

$$KE = \tfrac{1}{2}M_{SUV}V_{SUV}^{2} + \tfrac{1}{2}M_{VW}V_{VW}^{2}$$



120
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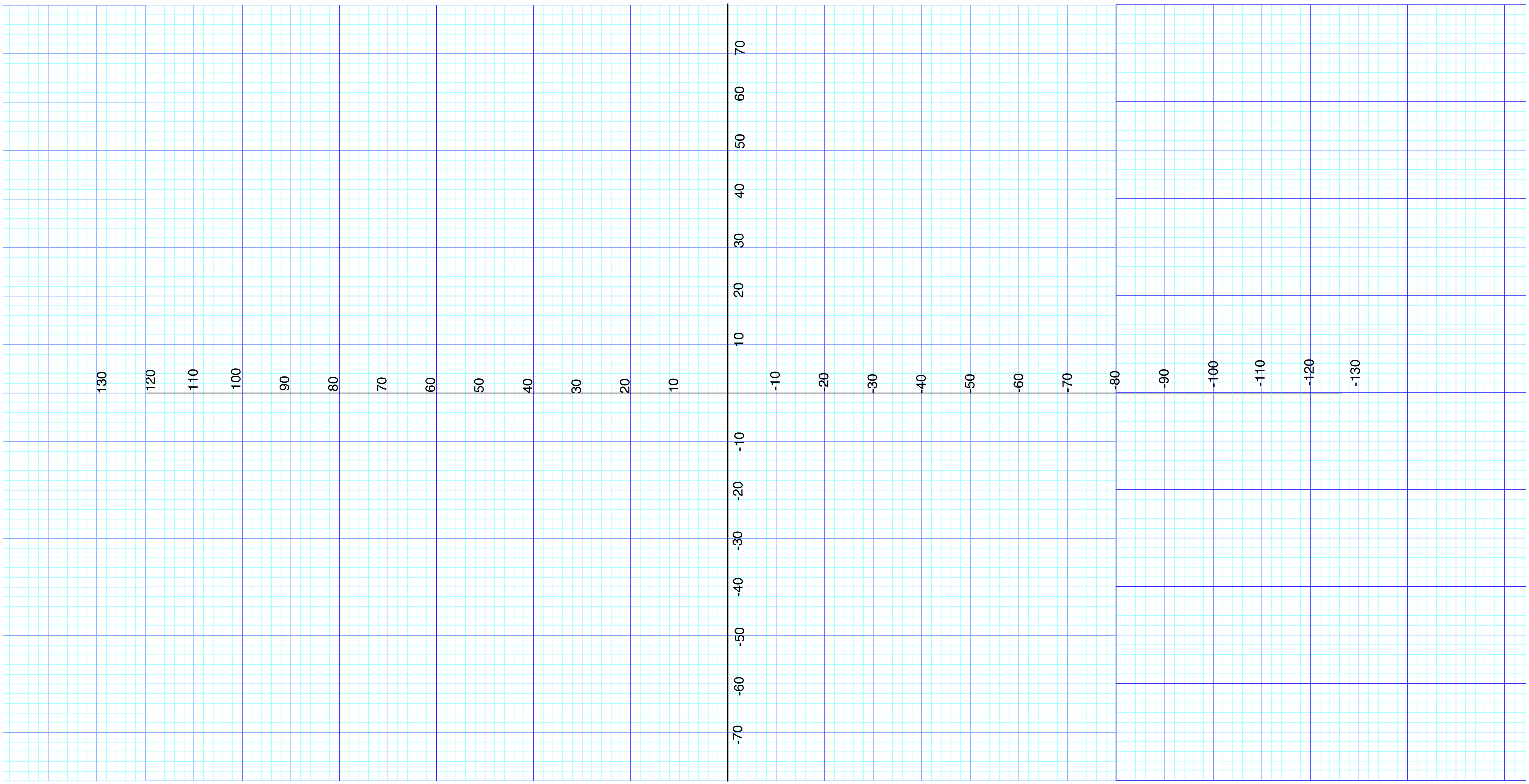
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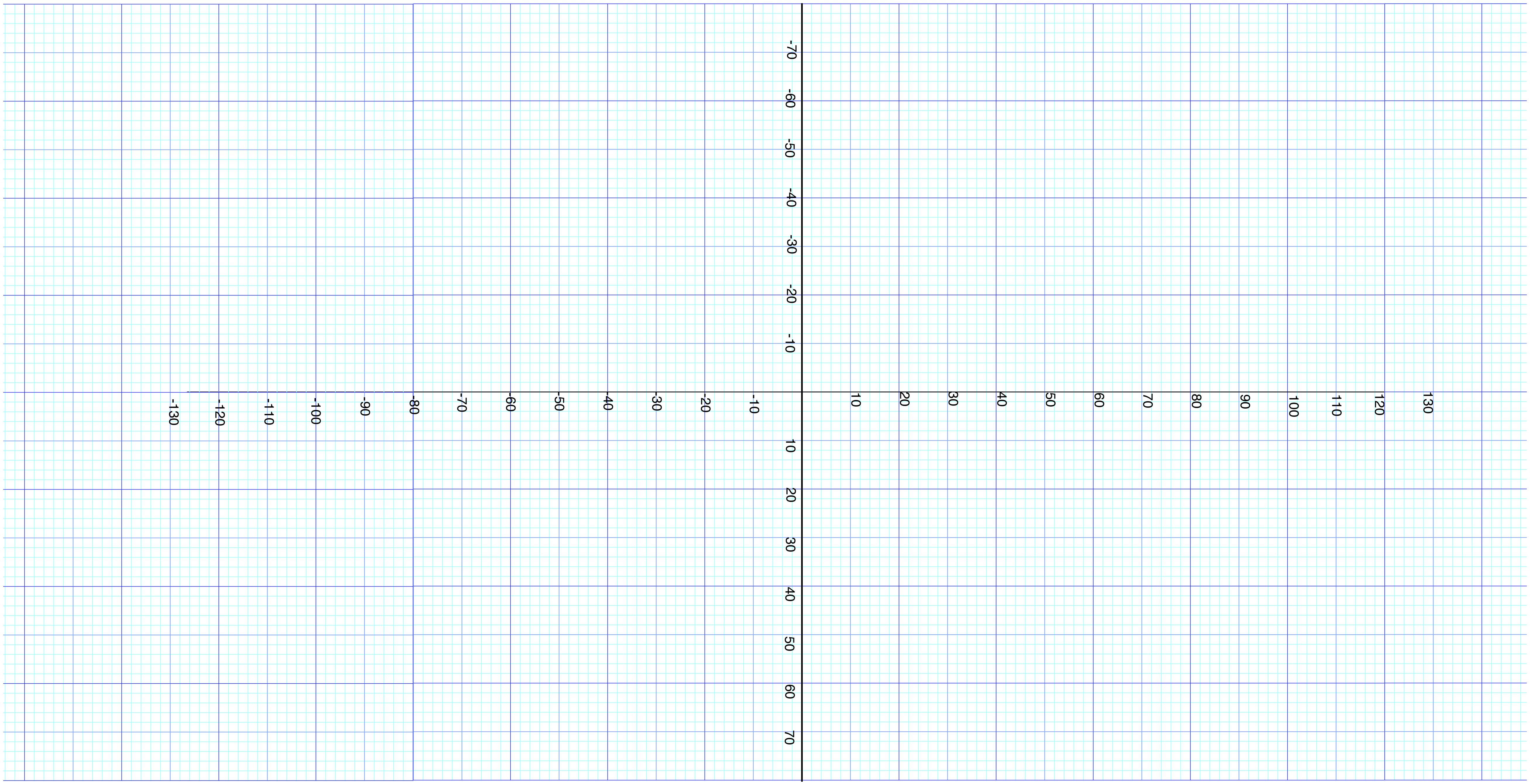
70 60 50 40 30 20 10
-10 -20 -30 -40 -50 -60 -70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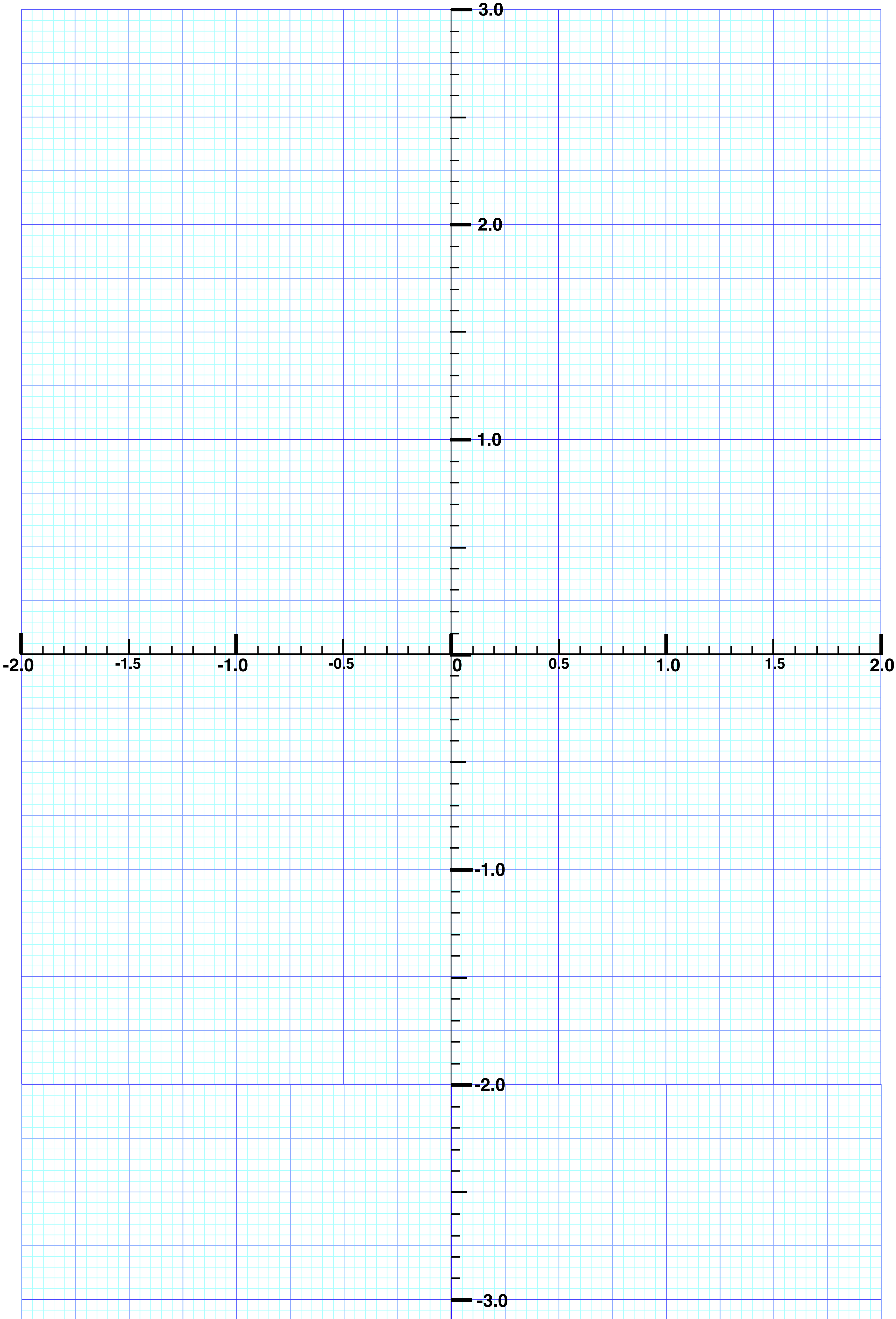

3.0
2.0
1.0
-2.0
-1.5
-1.0
-0.5
0
0.5
1.0
1.5
2.0
-1.0
-2.0
-3.0

Note “crunch” energy $_{Elastic}KE - _{inelastic}IE = 0.21$
is the same in all frames including COM-frame.

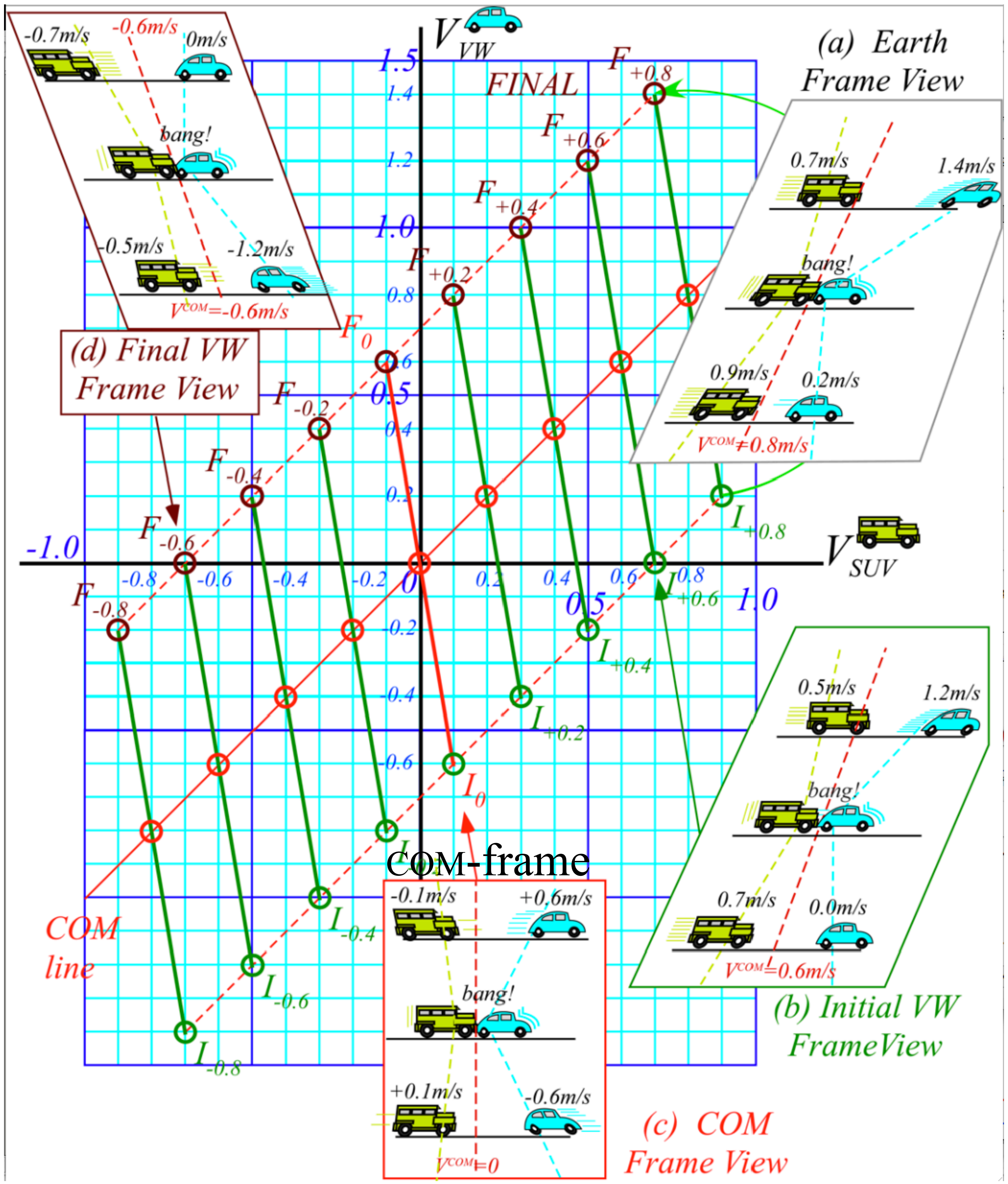

Fig. 3.4 Galilean Frame Views of collision like Fig. 2.5 or Fig. 3.1 with Bush (6:1) SUV.
(a) Earth frame view (b) Initial VW frame (VW initially fixed)
(c) COM frame view (d) Final VW frame (VW ends up fixed)

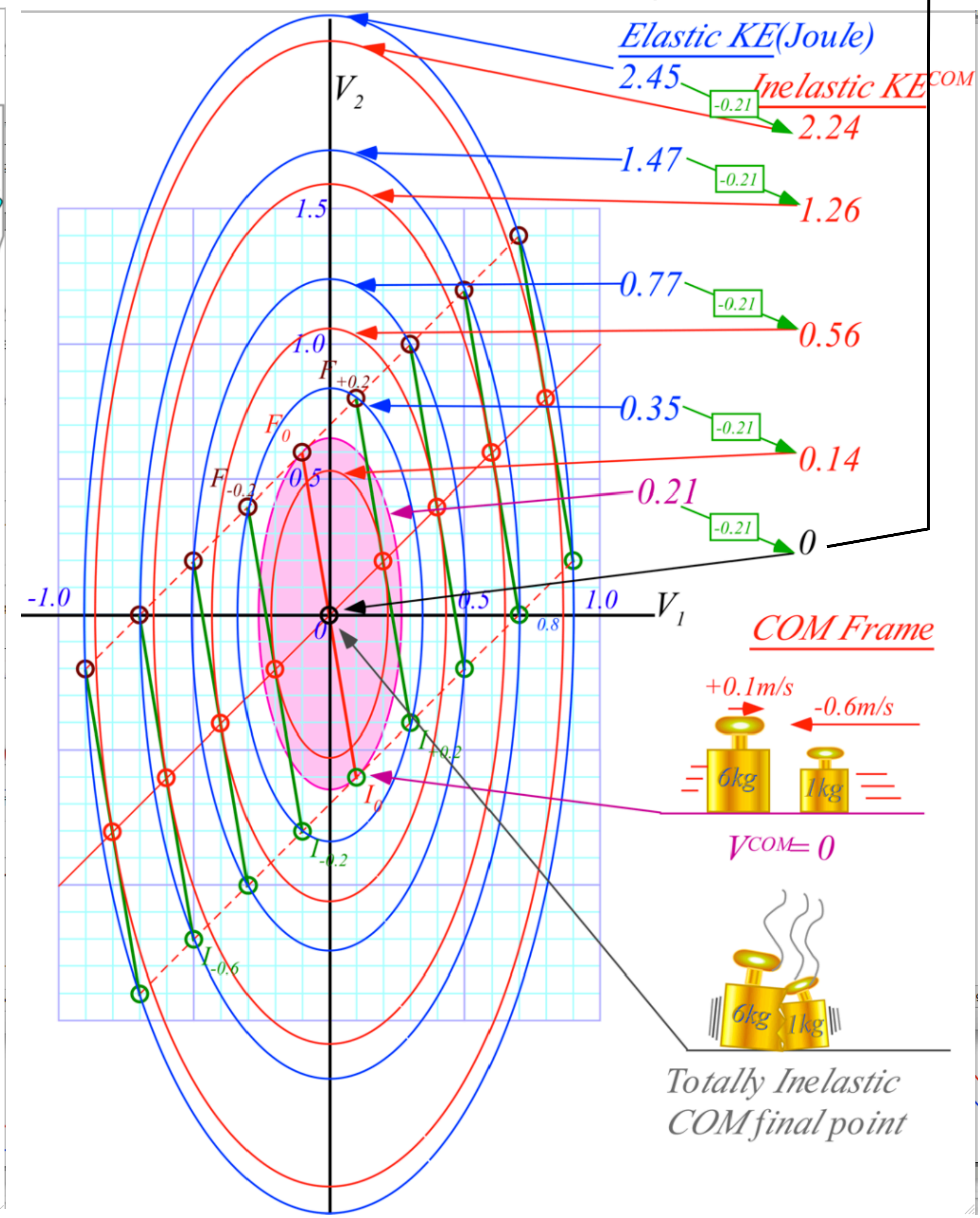

Fig. 3.5 Momentum (P=const.)-lines and energy (KE=const.)-ellipses appropriate for Fig. 3.4.