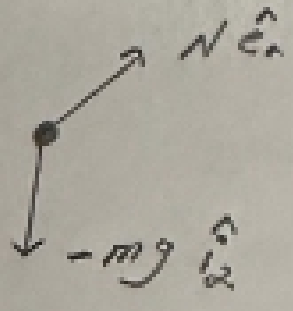


Let frame \hat{i} be inertially fixed at point O and let \hat{e} frame be fixed at point A.

$\hat{i} = \hat{e} = \hat{i}$, $\hat{r}^{OP} = -R\hat{e}_r$
 $\hat{e}_r, \hat{e}_\theta, \hat{e}_n$

(a) FBD:



(b) compute the work:

$W = T_0(t_2) - T_0(t_1) = \frac{1}{2} m |\dot{\vec{r}}^{OP}|^2 \Big|_{t_1}^{t_2}$
 $\vec{r}^{OP} = -R\hat{e}_r$, $\dot{\vec{r}}^{OP} = (\dot{\hat{e}}_\theta \times \vec{r}^{OP})$
 $\dot{\vec{r}}^{OP} = (\dot{\phi}\hat{e}_\theta \times -R\hat{e}_r) = -R\dot{\phi}\hat{e}_\theta$

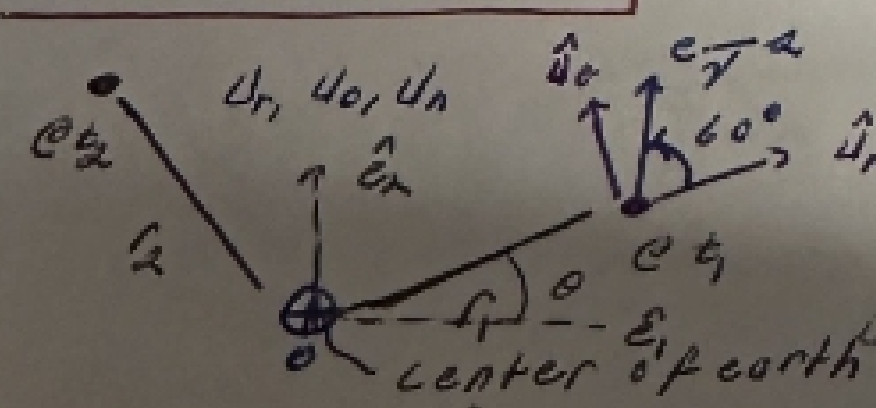
(b) $W = \int_{t_1}^{t_2} \vec{F}_p \cdot \dot{\vec{r}}^{OP} dt = \int_{t_1}^{t_2} (N\hat{e}_r \cdot -R\dot{\phi}\hat{e}_\theta) dt = 0$ b/c the normal force is a constraint force \perp to the path. Gravity is a conservative force b/c there is a scalar potential function: mgh . Work by gravity: $W = \int_{t_1}^{t_2} (-mg(\cos\phi\hat{e}_\theta + \sin\phi\hat{e}_r)) \cdot (-R\dot{\phi}\hat{e}_\theta) dt$

$W = \int_{t_1}^{t_2} mgR\sin\phi \dot{\phi} dt = \int_{\phi_1}^{\phi_2} mgR\sin\phi d\phi = \boxed{mgR(\cos\phi_1 - \cos\phi_2) = W}$

OR $h = R\sin\phi = \hat{i}_z \cdot (-R\hat{e}_r) = -R\hat{e}_r \cdot (\cos\phi\hat{e}_\theta + \sin\phi\hat{e}_r)$ $\phi_1 = \phi(t_1)$, $\phi_2 = \phi(t_2)$

(c) $D = E(t_2) - E(t_1)$, what is D expected to be? D should be zero or extremely close b/c there are no non conservative forces and total energy must be therefore conserved.

E2 PRACTICE 2



(a) FBD:

$F_g = \frac{-2M_e m_e}{r^2} \hat{u}_r$

(b) $\vec{r}^{OP} = r\hat{u}_r$, $\dot{\vec{r}}^{OP} = \dot{r}\hat{u}_r + r\dot{\theta}\hat{u}_\theta$

$\ddot{\vec{r}}^{OP} = \ddot{r}\hat{u}_r + (\dot{r}\dot{\theta} + r\ddot{\theta})\hat{u}_\theta + [(\dot{\theta}\hat{u}_r) \times \dot{\vec{r}}^{OP}]$

$\ddot{\vec{r}}^{OP} = \ddot{r}\hat{u}_r + (\dot{r}\dot{\theta} + r\ddot{\theta})\hat{u}_\theta + \dot{\theta}^2 r\hat{u}_r$

$\ddot{\vec{r}}^{OP} = (\ddot{r} - r\dot{\theta}^2)\hat{u}_r + (2\dot{r}\dot{\theta} + r\ddot{\theta})\hat{u}_\theta$, $F_{ext} = m\ddot{\vec{r}}^{OP}$

$-\frac{2M_e m_e}{r^2} \hat{u}_r = (\ddot{r} - r\dot{\theta}^2)\hat{u}_r + (2\dot{r}\dot{\theta} + r\ddot{\theta})\hat{u}_\theta$

(b) $\ddot{r} - r\dot{\theta}^2 = -\frac{M}{r^2}$, $r\ddot{\theta} = -2\dot{r}\dot{\theta}$

$\ddot{r} - r\dot{\theta}^2 = -\frac{M}{r^2}$

$\dot{\theta}' + \frac{2r\dot{\theta}'}{r} = 0$

(c) $r_1 = 6771 \text{ km}$, $r_2 = 6871 \text{ km}$, $25 = \frac{v_1^2}{2} + \frac{v_2^2}{2}$
 $E(t_1) = E(t_2)$, $\frac{1}{2} m |\dot{\vec{r}}_1|^2 - \frac{Mm}{r_1} = \frac{1}{2} m |\dot{\vec{r}}_2|^2 - \frac{Mm}{r_2}$ $h_0 = \text{constant}$
 $\frac{1}{2} (25) - \frac{M}{6771} = \frac{1}{2} |\dot{\vec{r}}_2|^2 - \frac{M}{6871}$ $v_2^2 = 25.2864 = v_2^2 + v_\theta^2$, $v_1 = 2.0523$ $v_2 = \frac{v_1}{2} + \frac{v_\theta}{2}$

$\vec{v}_2 = 0.2525 \hat{u}_r + 1.268 \hat{u}_\theta$