

CLASS 9- WORKSHEET

CHAPTER – MOTION

Problems

- 1 An object travels 16m in 4s and then another 16m in 2s .What is average speed of object?
- 2 A body is moving with a velocity of 15m/s .If the motion is uniform ,what will be the velocity after 10s?
- 3 A body travel a distance of 15 m from A to B and then moves a distance of 20m at right angles to AB .Calculate the total distance travelled and the displacement?
- 4 A body thrown vertically upwards reaches a maximum height "h" .It then return to ground .Calculate the distance travelled and displacement .
- 5 A particle is moving in a circle of diameter 5m . Calculate the distance and the displacement when it completes 3 revolutions ?

Application level questions –

- 1 Can the average speed of moving body be zero.Give reason ?
- 2 What is slope under velocity -time graph represents ?
- 3 Under what condition , the average speed is equal to the magnitude of the average velocity?
- 4 Can an object be accelerated if it is moving with constant speed ?If yes ,explain giving examples ?
- 5 Plot the speed -time graph for the given motion of object
 - a For an object at uniform speed
 - b For an object in non uniform speed increasing
 - c For an object at rest
 - d For an object in non uniform speed decreasing

Chapter Motion For Free S

John D. Cutnell, Kenneth W. Johnson



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Advanced Theory of Constraint and Motion Analysis for Robot Mechanisms Jingshan Zhao,Zhijing Feng,Fulei Chu,Ning Ma,2013-11-22 *Advanced Theory of Constraint and Motion Analysis for Robot Mechanisms* provides a complete analytical approach to the invention of new robot mechanisms and the analysis of existing designs based on a unified mathematical description of the kinematic and geometric constraints of mechanisms Beginning with a high level introduction to mechanisms and components the book moves on to present a new analytical theory of terminal constraints for use in the development of new spatial mechanisms and structures It clearly describes the application of screw theory to kinematic problems and provides tools that students engineers and researchers can use for investigation of critical factors such as workspace dexterity and singularity Combines constraint and free motion analysis and design offering a new approach to robot mechanism innovation and improvement Clearly describes the use of screw theory in robot kinematic analysis allowing for concise representation of motion and static forces when compared to conventional analysis methods Includes worked examples to translate theory into practice and demonstrate the application of new analytical methods to critical robotics problems

Dynamics Samuel Earnshaw,1844 [Handbook of Discrete and Computational Geometry](#) Csaba D. Toth,Joseph O'Rourke,Jacob E. Goodman,2017-11-22 The *Handbook of Discrete and Computational Geometry* is intended as a reference book fully accessible to nonspecialists as well as specialists covering all major aspects of both fields The book offers the most important results and methods in discrete and computational geometry to those who use them in their work both in the academic world as researchers in mathematics and computer science and in the professional world as practitioners in fields as diverse as operations research molecular biology and robotics Discrete geometry has contributed significantly to the growth of discrete mathematics in recent years This has been fueled partly by the advent of powerful computers and by the recent explosion of activity in the relatively young field of computational geometry This synthesis between discrete and computational geometry lies at the heart of this Handbook A growing list of application fields includes combinatorial optimization computer aided design computer graphics crystallography data analysis error correcting codes geographic information systems motion planning operations research pattern recognition robotics solid modeling and tomography

Quantum Mechanics Eugen Merzbacher,1998-01-14 Rapid advances in quantum optics atomic physics particle physics and other areas have been driven by fantastic progress in instrumentation especially lasers and computing technology as well as by the ever increasing emphasis on symmetry and information concepts requiring that all physicists receive a thorough grounding in quantum mechanics This book provides a carefully structured and complete exposition of quantum mechanics and illustrates the common threads linking many different phenomena and subfields of physics

Physics, Volume One: Chapters 1-17 John D. Cutnell,Kenneth W. Johnson,2014-12-15 Cutnell and Johnson has been the 1 text in the algebra based physics market for almost 20 years The 10th edition brings on new co authors David Young

and Shane Stadler both out of LSU The Cutnell offering now includes enhanced features and functionality The authors have been extensively involved in the creation and adaptation of valuable resources for the text This edition includes chapters 1 17

College Physics Textbook Equity Edition Volume 1 of 3: Chapters 1 - 12 An OER from Textbook Equity, 2014-01-13
Authored by Openstax College CC BY An OER Edition by Textbook Equity Edition 2012 This text is intended for one year introductory courses requiring algebra and some trigonometry but no calculus College Physics is organized such that topics are introduced conceptually with a steady progression to precise definitions and analytical applications The analytical aspect problem solving is tied back to the conceptual before moving on to another topic Each introductory chapter for example opens with an engaging photograph relevant to the subject of the chapter and interesting applications that are easy for most students to visualize For manageability the original text is available in three volumes Full color PDF s are free at www.textbookequity.org

The Complexity of Robot Motion Planning John Canny, 1988 The Complexity of Robot Motion Planning makes original contributions both to robotics and to the analysis of algorithms In this groundbreaking monograph John Canny resolves long standing problems concerning the complexity of motion planning and for the central problem of finding a collision free path for a jointed robot in the presence of obstacles obtains exponential speedups over existing algorithms by applying high powered new mathematical techniques Canny's new algorithm for this generalized movers problem the most studied and basic robot motion planning problem has a single exponential running time and is polynomial for any given robot The algorithm has an optimal running time exponent and is based on the notion of roadmaps one dimensional subsets of the robot's configuration space In deriving the single exponential bound Canny introduces and reveals the power of two tools that have not been previously used in geometrical algorithms the generalized multivariable resultant for a system of polynomials and Whitney's notion of stratified sets He has also developed a novel representation of object orientation based on unnormalized quaternions which reduces the complexity of the algorithms and enhances their practical applicability After dealing with the movers problem the book next attacks and derives several lower bounds on extensions of the problem finding the shortest path among polyhedral obstacles planning with velocity limits and compliant motion planning with uncertainty It introduces a clever technique path encoding that allows a proof of NP hardness for the first two problems and then shows that the general form of compliant motion planning a problem that is the focus of a great deal of recent work in robotics is non deterministic exponential time hard Canny proves this result using a highly original construction John Canny received his doctorate from MIT and is an assistant professor in the Computer Science Division at the University of California Berkeley The Complexity of Robot Motion Planning is the winner of the 1987 ACM Doctoral Dissertation Award

On the Steady Motion of a Coupled System Solid-Liquid Josef Bemelmans, Giovanni Paolo Galdi, Mads Kyed, 2013-10-23 We study the unconstrained free motion of an elastic solid B in a Navier Stokes liquid L occupying the whole space outside B under the assumption that a constant body force b is acting on B More specifically we are interested in

the steady motion of the coupled system $B \cdot L$ which means that there exists a frame with respect to which the relevant governing equations possess a time independent solution We prove the existence of such a frame provided some smallness restrictions are imposed on the physical parameters and the reference configuration of B satisfies suitable geometric properties

Robot Motion Planning Jean-Claude Latombe, 2012-12-06 One of the ultimate goals in Robotics is to create autonomous robots Such robots will accept high level descriptions of tasks and will execute them without further human intervention The input descriptions will specify what the user wants done rather than how to do it The robots will be any kind of versatile mechanical device equipped with actuators and sensors under the control of a computing system Making progress toward autonomous robots is of major practical interest in a wide variety of application domains including manufacturing construction waste management space exploration undersea work assistance for the disabled and medical surgery It is also of great technical interest especially for Computer Science because it raises challenging and rich computational issues from which new concepts of broad usefulness are likely to emerge Developing the technologies necessary for autonomous robots is a formidable undertaking with deep interweaved ramifications in automated reasoning perception and control It raises many important problems One of them motion planning is the central theme of this book It can be loosely stated as follows How can a robot decide what motions to perform in order to achieve goal arrangements of physical objects This capability is eminently necessary since by definition a robot accomplishes tasks by moving in the real world The minimum one would expect from an autonomous robot is the ability to plan its own motions

Computational Geometry Mark de Berg, Otfried Cheong, Marc van Kreveld, Mark Overmars, 2008-03-07 Computational geometry emerged from the field of algorithms design and analysis in the late 1970s It has grown into a recognized discipline with its own journals conferences and a large community of active researchers The success of the field as a research discipline can on the one hand be explained from the beauty of the problems studied and the solutions obtained and on the other hand by the many application domains computer graphics geographic information systems GIS robotics and others in which geometric algorithms play a fundamental role For many geometric problems the early algorithmic solutions were either slow or difficult to understand and implement In recent years a number of new algorithmic techniques have been developed that improved and simplified many of the previous approaches In this textbook we have tried to make these modern algorithmic solutions accessible to a large audience The book has been written as a textbook for a course in computational geometry but it can also be used for self study

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