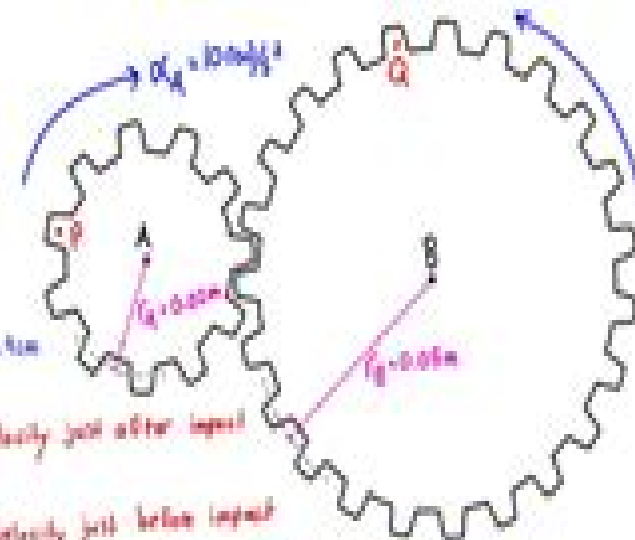
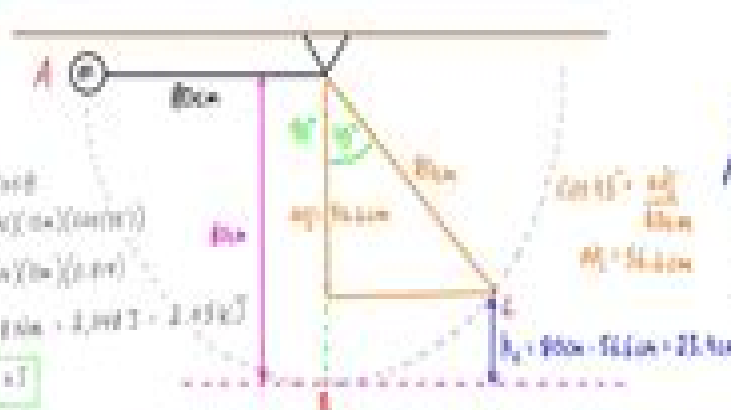




$m = 1048 \text{ kg}$
 $v_i = 0$
 $v_f = 100 \text{ km/h}$
 $t = 37 \text{ s}$
 $P_{avg} = ?$

$W = F \cdot d \cos \theta$
 $W = (3500 \text{ N}) \cdot (100 \text{ m}) \cos(0^\circ)$
 $W = (3500 \text{ N}) \cdot (100 \text{ m}) \cdot (1.0)$
 $W = 3.5 \times 10^5 \text{ J}$
 $P = \frac{W}{t} = \frac{3.5 \times 10^5 \text{ J}}{37 \text{ s}} = 9.46 \times 10^3 \text{ W}$
 $P = 9.46 \text{ kW}$

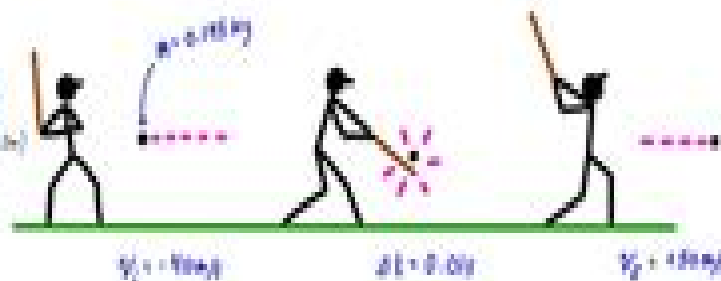


$e = \frac{v_{B1} - v_{A1}}{v_{A1} - v_{B1}}$
 relative velocity just after impact
 relative velocity just before impact

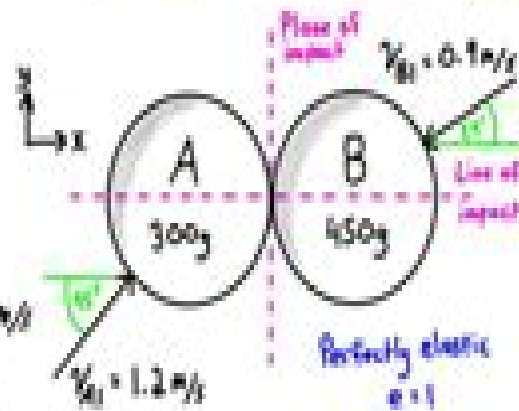
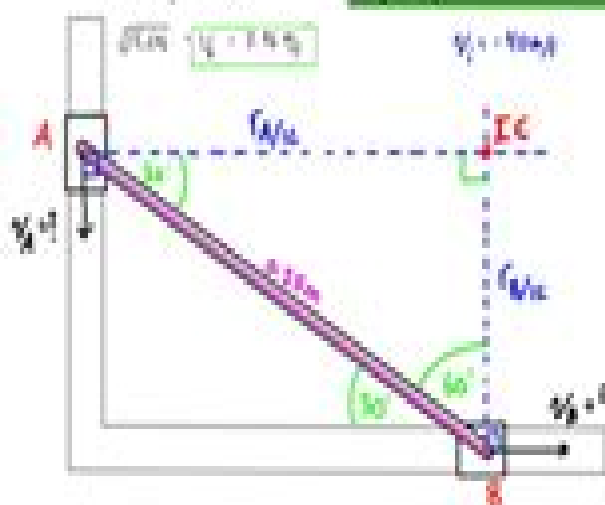
Write conservation of momentum in x direction

momentum before = momentum after
 $m_A v_{Ax1} + m_B v_{Bx1} = m_A v_{Ax2} + m_B v_{Bx2}$
 $(0.3 \text{ kg})(0.449 \text{ m/s}) + (0.45 \text{ kg})(0.449 \text{ m/s}) = (0.3 \text{ kg})v_{Ax2} + (0.45 \text{ kg})v_{Bx2}$
 $0.2547 \text{ kg} \cdot \text{m/s} + 0.20205 \text{ kg} \cdot \text{m/s} = 0.3 \text{ kg} v_{Ax2} + 0.45 \text{ kg} v_{Bx2}$
 $0.45675 \text{ kg} \cdot \text{m/s} = 0.3 \text{ kg} v_{Ax2} + 0.45 \text{ kg} v_{Bx2}$
 $0.45675 \text{ m/s} = 0.3 v_{Ax2} + 0.45 v_{Bx2}$

$T_1 + U_1 = T_2 + U_2$
 $\frac{1}{2}mv_1^2 + mgh_1 = \frac{1}{2}mv_2^2 + mgh_2$
 $\frac{1}{2}(1 \text{ kg})(1 \text{ m/s})^2 + (1 \text{ kg})(9.8 \text{ m/s}^2)(1 \text{ m}) = \frac{1}{2}(1 \text{ kg})v_2^2 + (1 \text{ kg})(9.8 \text{ m/s}^2)(2 \text{ m})$
 $0.5 \text{ J} + 9.8 \text{ J} = 0.5 v_2^2 + 19.6 \text{ J}$
 $10.3 \text{ J} = 0.5 v_2^2 + 19.6 \text{ J}$
 $0.5 v_2^2 = 10.3 \text{ J} - 19.6 \text{ J} = -9.3 \text{ J}$
 $v_2^2 = -18.6 \text{ m}^2/\text{s}^2$
 $v_2 = 4.3 \text{ m/s}$



Notice that 0.45675 is the "momentum before"



Initial kinetic energy $T_i + \sum U_{1-2} = T_f$ (Final kinetic energy)
 $T_i = \frac{1}{2}mv_i^2$
 $T_f = \frac{1}{2}mv_f^2$
 $\sum U_{1-2} = F_s \cos \theta$ (Force of friction)
 No because friction opposes the motion

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Dynamic Reconfigurable Network-on-Chip Design: Innovations for Computational Processing and Communication Shen, Jih-Sheng, Hsiung, Pao-Ann, 2010-06-30 Reconfigurable computing brings immense flexibility to on chip processing while network on chip has improved flexibility in on chip communication Integrating these two areas of research reaps the benefits of both and represents the promising future of multiprocessor systems on chip This book is the one of the first compilations written to demonstrate this future for network on chip design Through dynamic and creative research into questions ranging from integrating reconfigurable computing techniques to task assigning scheduling and arrival to designing an operating system to take advantage of the computing and communication flexibilities brought about by run time reconfiguration and network on chip it represents a complete source of the techniques and applications for reconfigurable network on chip necessary for understanding of future of this field **University of Kentucky Catalogue** University of Kentucky, 1911 Mechanical Engineering, 1919 Catalog Issue for ... University of Oklahoma, 1910 *Automobile Engineer*, 1914 **Western Engineering**, 1916 **Iron and Steel Engineer**, 1928 *Engineering Education* American Society for Engineering Education, Society for the Promotion of Engineering Education (U.S.), 1906 Proceedings ... Papers, Reports, Discussions, Etc., Printed in the Journal of Engineering Education American Society for Engineering Education, 1906 **Dynamo, Motor and Switchboard Circuits for Electrical Engineers** William Rushton Bowker, 1904 **Electrical Engineering**, 1908 Announcements for the Year ... Purdue University, 1897 *The Annual Catalogue of Purdue University, Lafayette, Indiana ... with Announcements for ...* Purdue University, 1907

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Table of Contents Design Supp Engineering Dynam

1. Understanding the eBook Design Supp Engineering Dynam
 - The Rise of Digital Reading Design Supp Engineering Dynam
 - Advantages of eBooks Over Traditional Books
2. Identifying Design Supp Engineering Dynam
 - Exploring Different Genres
 - Considering Fiction vs. Non-Fiction
 - Determining Your Reading Goals
3. Choosing the Right eBook Platform
 - Popular eBook Platforms
 - Features to Look for in an Design Supp Engineering Dynam
 - User-Friendly Interface
4. Exploring eBook Recommendations from Design Supp Engineering Dynam
 - Personalized Recommendations
 - Design Supp Engineering Dynam User Reviews and Ratings
 - Design Supp Engineering Dynam and Bestseller Lists

5. Accessing Design Supp Engineering Dynam Free and Paid eBooks
 - Design Supp Engineering Dynam Public Domain eBooks
 - Design Supp Engineering Dynam eBook Subscription Services
 - Design Supp Engineering Dynam Budget-Friendly Options
6. Navigating Design Supp Engineering Dynam eBook Formats
 - ePub, PDF, MOBI, and More
 - Design Supp Engineering Dynam Compatibility with Devices
 - Design Supp Engineering Dynam Enhanced eBook Features
7. Enhancing Your Reading Experience
 - Adjustable Fonts and Text Sizes of Design Supp Engineering Dynam
 - Highlighting and Note-Taking Design Supp Engineering Dynam
 - Interactive Elements Design Supp Engineering Dynam
8. Staying Engaged with Design Supp Engineering Dynam
 - Joining Online Reading Communities
 - Participating in Virtual Book Clubs
 - Following Authors and Publishers Design Supp Engineering Dynam
9. Balancing eBooks and Physical Books Design Supp Engineering Dynam
 - Benefits of a Digital Library
 - Creating a Diverse Reading Collection Design Supp Engineering Dynam
10. Overcoming Reading Challenges
 - Dealing with Digital Eye Strain
 - Minimizing Distractions
 - Managing Screen Time
11. Cultivating a Reading Routine Design Supp Engineering Dynam
 - Setting Reading Goals Design Supp Engineering Dynam
 - Carving Out Dedicated Reading Time
12. Sourcing Reliable Information of Design Supp Engineering Dynam
 - Fact-Checking eBook Content of Design Supp Engineering Dynam
 - Distinguishing Credible Sources
13. Promoting Lifelong Learning

- Utilizing eBooks for Skill Development
- Exploring Educational eBooks

14. Embracing eBook Trends

- Integration of Multimedia Elements
- Interactive and Gamified eBooks

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