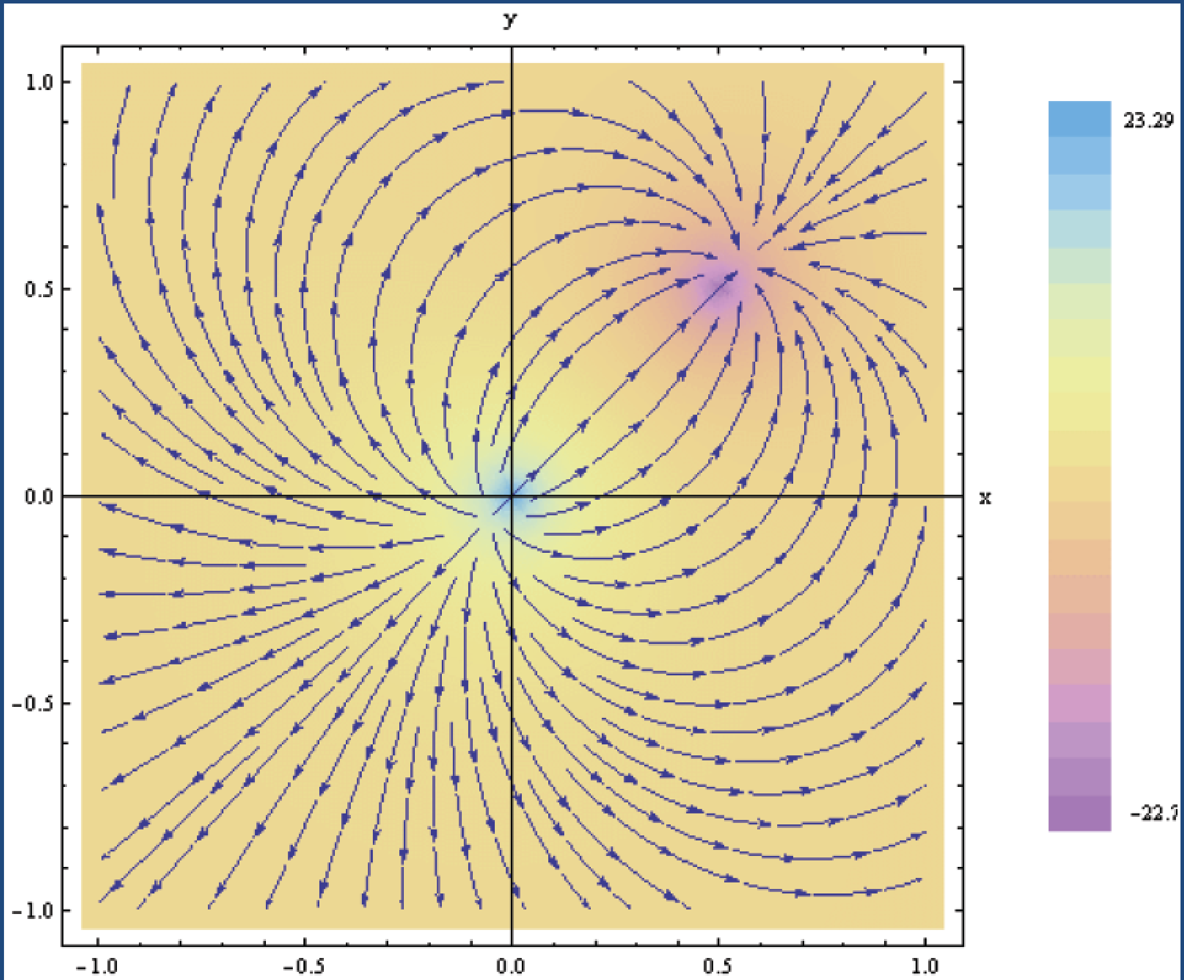
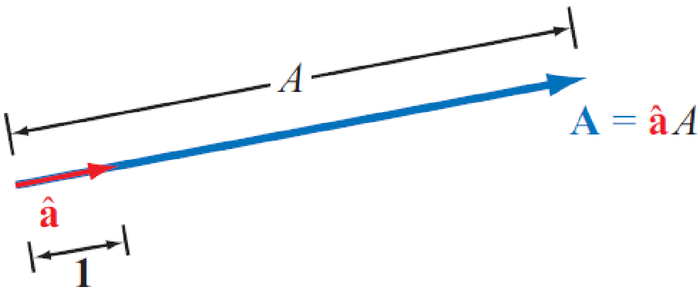


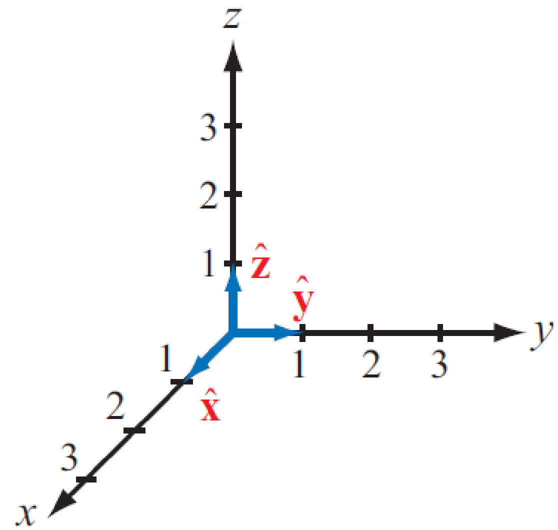
3. VECTOR ANALYSIS

Chapter 3: Vector Analysis

Laws of Vector Algebra



$$\mathbf{A} = \hat{\mathbf{a}}|\mathbf{A}| = \hat{\mathbf{a}}A$$

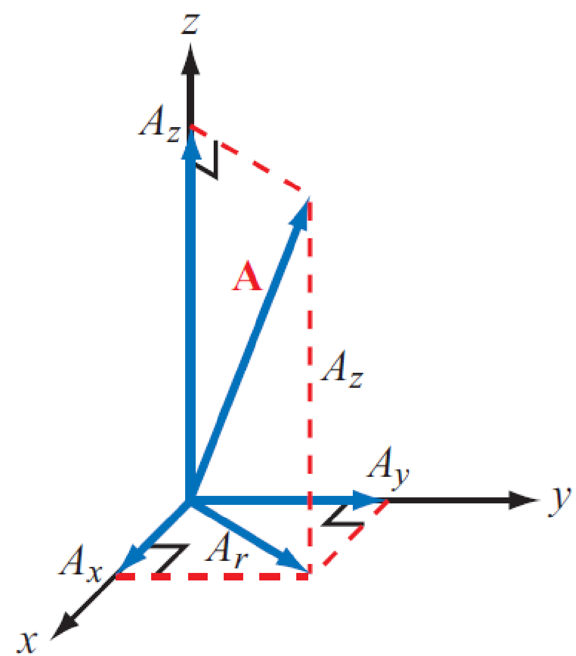


(a) Base vectors

$$\mathbf{A} = \hat{\mathbf{x}}A_x + \hat{\mathbf{y}}A_y + \hat{\mathbf{z}}A_z$$

$$A = |\mathbf{A}| = \sqrt[+]{A_x^2 + A_y^2 + A_z^2}$$

$$\hat{\mathbf{a}} = \frac{\mathbf{A}}{A} = \frac{\hat{\mathbf{x}}A_x + \hat{\mathbf{y}}A_y + \hat{\mathbf{z}}A_z}{\sqrt[+]{A_x^2 + A_y^2 + A_z^2}}$$



(b) Components of **A**

Properties of Vector Operations

Equality of Two Vectors

$$\mathbf{A} = \hat{\mathbf{a}}A = \hat{\mathbf{x}}A_x + \hat{\mathbf{y}}A_y + \hat{\mathbf{z}}A_z, \quad (3.6a)$$

$$\mathbf{B} = \hat{\mathbf{b}}B = \hat{\mathbf{x}}B_x + \hat{\mathbf{y}}B_y + \hat{\mathbf{z}}B_z, \quad (3.6b)$$

then $\mathbf{A} = \mathbf{B}$ if and only if $A = B$ and $\hat{\mathbf{a}} = \hat{\mathbf{b}}$, which requires that $A_x = B_x$, $A_y = B_y$, and $A_z = B_z$.

Equal Vectors!

Commutative property

$$\mathbf{C} = \mathbf{A} + \mathbf{B} = \mathbf{B} + \mathbf{A}$$

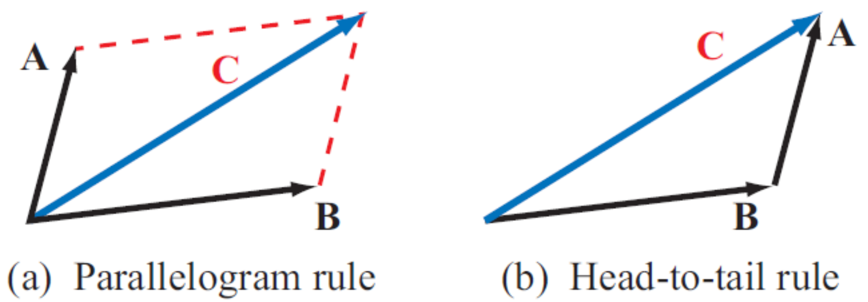


Figure 3-3: Vector addition by (a) the parallelogram rule and (b) the head-to-tail rule.

Vector Multiplication: Scalar Product or "Dot Product"

$$\mathbf{A}\cdot\mathbf{B} = AB\cos\theta_{AB}$$

$$A = |\mathbf{A}| = \sqrt[+]{\mathbf{A}\cdot\mathbf{A}}$$

$$\theta_{AB} = \cos^{-1}\left[\frac{\mathbf{A}\cdot\mathbf{B}}{\sqrt[+]{\mathbf{A}\cdot\mathbf{A}}\,\sqrt[+]{\mathbf{B}\cdot\mathbf{B}}}\right]$$

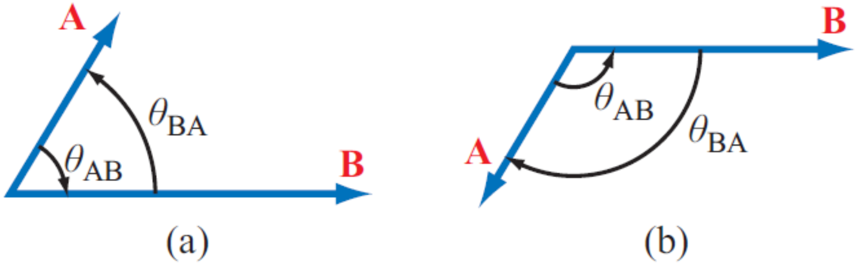


Figure 3-5: The angle θ_{AB} is the angle between **A** and **B**, measured from **A** to **B** between vector tails. The dot product is positive if $0 \le \theta_{AB} < 90°$, as in (a), and it is negative if $90° < \theta_{AB} \le 180°$, as in (b).

$$\hat{\mathbf{x}}\cdot\hat{\mathbf{x}} = \hat{\mathbf{y}}\cdot\hat{\mathbf{y}} = \hat{\mathbf{z}}\cdot\hat{\mathbf{z}} = 1,$$
$$\hat{\mathbf{x}}\cdot\hat{\mathbf{y}} = \hat{\mathbf{y}}\cdot\hat{\mathbf{z}} = \hat{\mathbf{z}}\cdot\hat{\mathbf{x}} = 0.$$

$$\mathbf{A}\cdot\mathbf{B} = \mathbf{B}\cdot\mathbf{A} \quad \text{(commutative property)},$$

$$\mathbf{A}\cdot(\mathbf{B}+\mathbf{C}) = \mathbf{A}\cdot\mathbf{B} + \mathbf{A}\cdot\mathbf{C} \quad \text{(distributive property)}$$

If $\mathbf{A} = (A_x, A_y, A_z)$ and $\mathbf{B} = (B_x, B_y, B_z)$, then

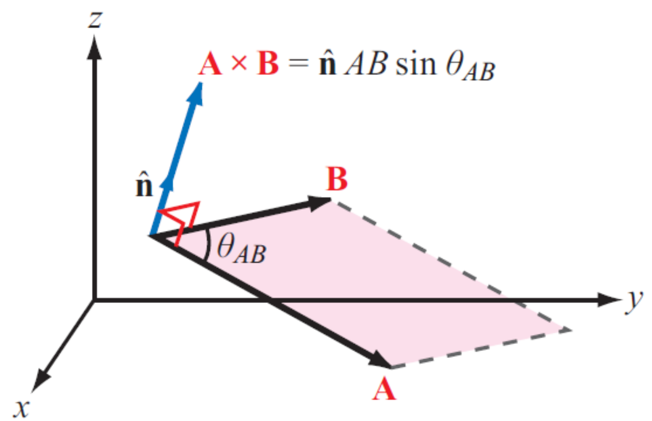
$$\mathbf{A}\cdot\mathbf{B} = (\hat{\mathbf{x}}A_x + \hat{\mathbf{y}}A_y + \hat{\mathbf{z}}A_z)\cdot(\hat{\mathbf{x}}B_x + \hat{\mathbf{y}}B_y + \hat{\mathbf{z}}B_z).$$

Hence:

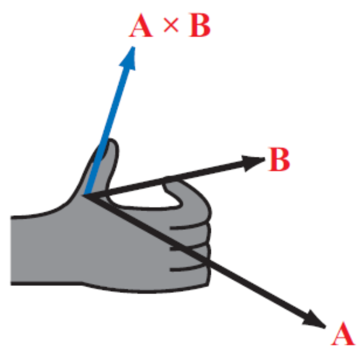
$$\mathbf{A}\cdot\mathbf{B} = A_xB_x + A_yB_y + A_zB_z.$$

Vector Multiplication: Vector Product or "Cross Product"

$$\mathbf{A} \times \mathbf{B} = \hat{\mathbf{n}}\, AB \sin\theta_{AB}$$



(a) Cross product



(b) Right-hand rule

$$\mathbf{A} \times \mathbf{B} = -\mathbf{B} \times \mathbf{A} \qquad \text{(anticommutative)}$$

$$\mathbf{A} \times (\mathbf{B} + \mathbf{C}) = \mathbf{A} \times \mathbf{B} + \mathbf{A} \times \mathbf{C} \qquad \text{(distributive)}$$

$$\mathbf{A} \times \mathbf{A} = 0$$

$$\hat{\mathbf{x}} \times \hat{\mathbf{y}} = \hat{\mathbf{z}}, \qquad \hat{\mathbf{y}} \times \hat{\mathbf{z}} = \hat{\mathbf{x}}, \qquad \hat{\mathbf{z}} \times \hat{\mathbf{x}} = \hat{\mathbf{y}}. \qquad (3.25)$$

Note the cyclic order $(xyzxyz\ldots)$. Also,

$$\hat{\mathbf{x}} \times \hat{\mathbf{x}} = \hat{\mathbf{y}} \times \hat{\mathbf{y}} = \hat{\mathbf{z}} \times \hat{\mathbf{z}} = 0. \qquad (3.26)$$

If $\mathbf{A} = (A_x, A_y, A_z)$ and $\mathbf{B} = (B_x, B_y, B_z)$,

$$\mathbf{A} \times \mathbf{B} = \begin{vmatrix} \hat{\mathbf{x}} & \hat{\mathbf{y}} & \hat{\mathbf{z}} \\ A_x & A_y & A_z \\ B_x & B_y & B_z \end{vmatrix}.$$

Example

Example 3-1: Vectors and Angles

In Cartesian coordinates, vector **A** points from the origin to point $P_1 = (2, 3, 3)$, and vector **B** is directed from P_1 to point $P_2 = (1, -2, 2)$. Find

(a) vector **A**, its magnitude A, and unit vector $\hat{\mathbf{a}}$,

(b) the angle between **A** and the y-axis,

(c) vector **B**,

(d) the angle θ_{AB} between **A** and **B**, and

(e) the perpendicular distance from the origin to vector **B**.

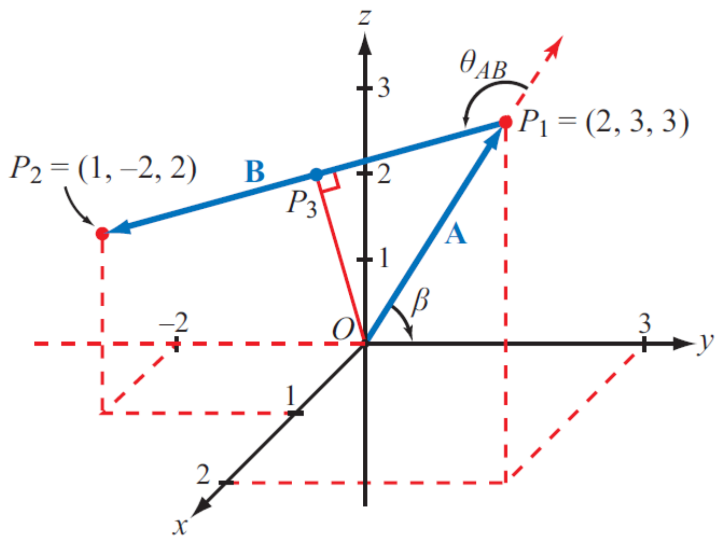
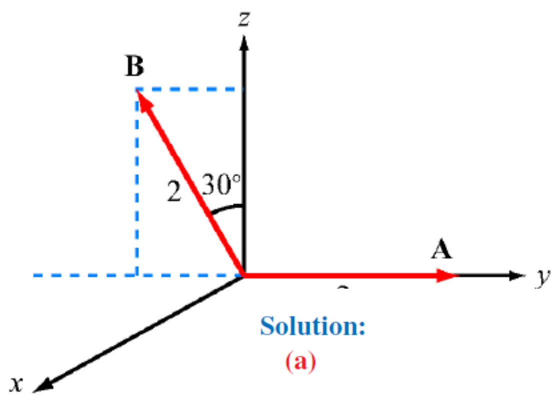


Figure 3-7: Geometry of Example 3-1.

Notes!

Example:

Vectors **A** and **B** lie in the *y*-*z* plane and both have the same magnitude of 2 . Determine (a) $\mathbf{A} \cdot \mathbf{B}$ and (b) $\mathbf{A} \times \mathbf{B}$.



Solution:

(a)

$$\begin{aligned}\mathbf{A} \cdot \mathbf{B} &= AB\cos(90^\circ + 30^\circ)\\ &= 2 \times 2 \times \cos 120^\circ\\ &= -2.\end{aligned}$$

(b)

$$\begin{aligned}\mathbf{A} &= \hat{\mathbf{y}}\,2\\ \mathbf{B} &= -\hat{\mathbf{y}}\,2\cos 60^\circ + \hat{\mathbf{z}}\,2\cos 30^\circ\\ &= -\hat{\mathbf{y}}\,1 + \hat{\mathbf{z}}\,1.73\\ \mathbf{A} \times \mathbf{B} &= \hat{\mathbf{y}}\,2 \times (-\hat{\mathbf{y}}\,1 + \hat{\mathbf{z}}\,1.73)\\ &= \hat{\mathbf{x}}\,3.46.\end{aligned}$$

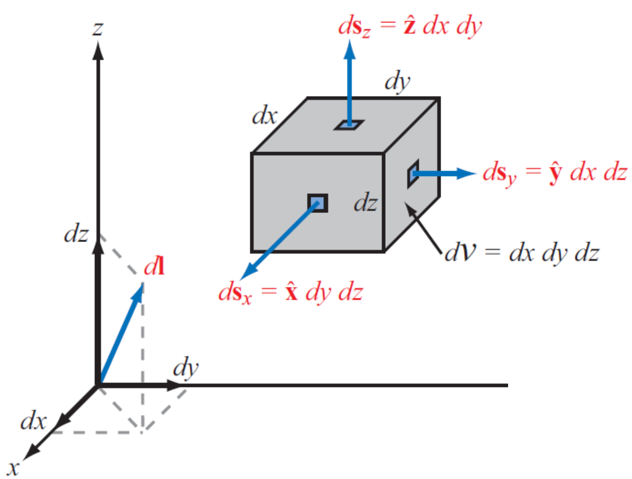
Example

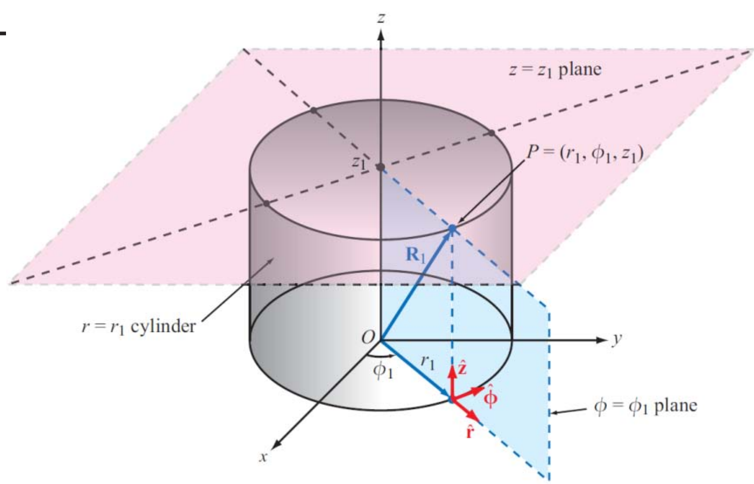
Example

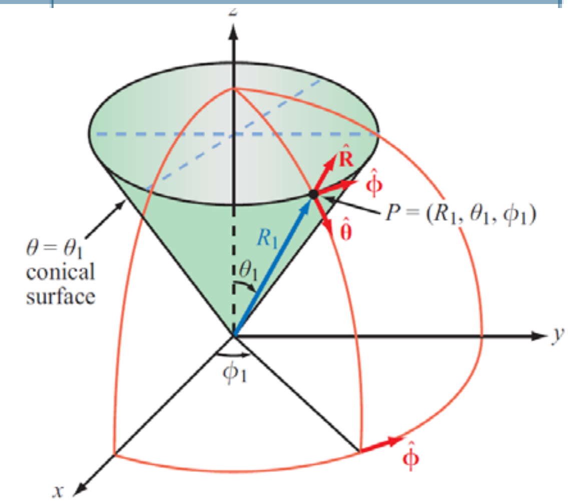
Given $\mathbf{A} = \hat{\mathbf{x}} - \hat{\mathbf{y}} + \hat{\mathbf{z}}2$, $\mathbf{B} = \hat{\mathbf{y}} + \hat{\mathbf{z}}$, and $\mathbf{C} = -\hat{\mathbf{x}}2 + \hat{\mathbf{z}}3$, find $(\mathbf{A} \times \mathbf{B}) \times \mathbf{C}$ and compare it with $\mathbf{A} \times (\mathbf{B} \times \mathbf{C})$.

Coordinate Systems

	Cartesian Coordinates	Cylindrical Coordinates	Spherical Coordinates
Coordinate variables	x, y, z	r, ϕ, z	R, θ, ϕ
Vector representation $\mathbf{A} =$	$\hat{\mathbf{x}}A_x + \hat{\mathbf{y}}A_y + \hat{\mathbf{z}}A_z$	$\hat{\mathbf{r}}A_r + \hat{\boldsymbol{\phi}}A_\phi + \hat{\mathbf{z}}A_z$	$\hat{\mathbf{R}}A_R + \hat{\boldsymbol{\theta}}A_\theta + \hat{\boldsymbol{\phi}}A_\phi$







Cartesian Coordinate System

Differential length vector

$$d\mathbf{l} = \hat{\mathbf{x}}\, dl_x + \hat{\mathbf{y}}\, dl_y + \hat{\mathbf{z}}\, dl_z = \hat{\mathbf{x}}\, dx + \hat{\mathbf{y}}\, dy + \hat{\mathbf{z}}\, dz, \quad (3.34)$$

Differential area vectors

$$d\mathbf{s}_x = \hat{\mathbf{x}}\, dl_y\, dl_z = \hat{\mathbf{x}}\, dy\, dz \qquad (y\text{–}z \text{ plane}), \qquad (3.35a)$$

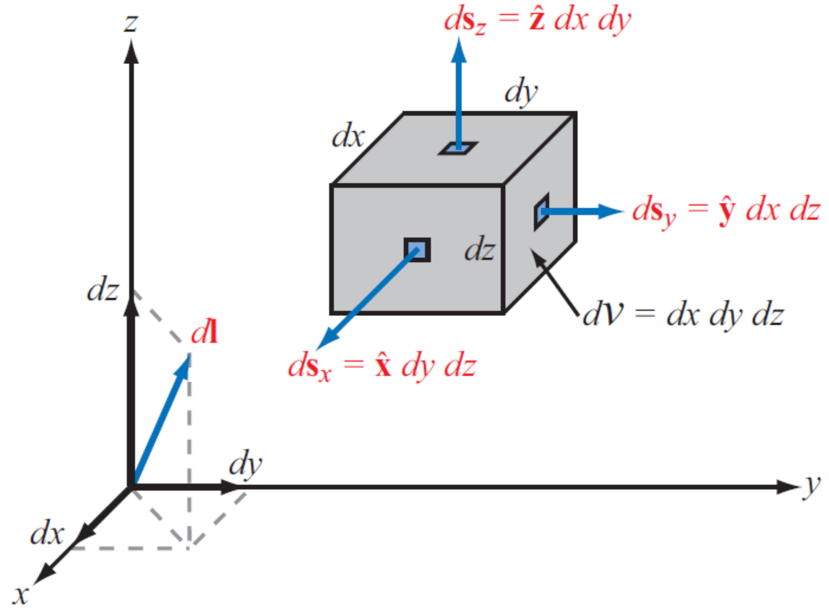


Table 3-1: Summary of vector relations.

	Cartesian Coordinates	Cylindrical Coordinates	Spherical Coordinates
Coordinate variables	x, y, z	r, ϕ, z	R, θ, ϕ
Vector representation $\mathbf{A} =$	$\hat{\mathbf{x}}A_x + \hat{\mathbf{y}}A_y + \hat{\mathbf{z}}A_z$	$\hat{\mathbf{r}}A_r + \hat{\boldsymbol{\phi}}A_\phi + \hat{\mathbf{z}}A_z$	$\hat{\mathbf{R}}A_R + \hat{\boldsymbol{\theta}}A_\theta + \hat{\boldsymbol{\phi}}A_\phi$
Magnitude of A $\quad |\mathbf{A}| =$	$\sqrt[+]{A_x^2 + A_y^2 + A_z^2}$	$\sqrt[+]{A_r^2 + A_\phi^2 + A_z^2}$	$\sqrt[+]{A_R^2 + A_\theta^2 + A_\phi^2}$
Position vector $\overrightarrow{OP_1} =$	$\hat{\mathbf{x}}x_1 + \hat{\mathbf{y}}y_1 + \hat{\mathbf{z}}z_1$, for $P = (x_1, y_1, z_1)$	$\hat{\mathbf{r}}r_1 + \hat{\mathbf{z}}z_1$, for $P = (r_1, \phi_1, z_1)$	$\hat{\mathbf{R}}R_1$, for $P = (R_1, \theta_1, \phi_1)$
Base vectors properties	$\hat{\mathbf{x}}\cdot\hat{\mathbf{x}} = \hat{\mathbf{y}}\cdot\hat{\mathbf{y}} = \hat{\mathbf{z}}\cdot\hat{\mathbf{z}} = 1$ $\hat{\mathbf{x}}\cdot\hat{\mathbf{y}} = \hat{\mathbf{y}}\cdot\hat{\mathbf{z}} = \hat{\mathbf{z}}\cdot\hat{\mathbf{x}} = 0$ $\hat{\mathbf{x}}\times\hat{\mathbf{y}} = \hat{\mathbf{z}}$ $\hat{\mathbf{y}}\times\hat{\mathbf{z}} = \hat{\mathbf{x}}$ $\hat{\mathbf{z}}\times\hat{\mathbf{x}} = \hat{\mathbf{y}}$	$\hat{\mathbf{r}}\cdot\hat{\mathbf{r}} = \hat{\boldsymbol{\phi}}\cdot\hat{\boldsymbol{\phi}} = \hat{\mathbf{z}}\cdot\hat{\mathbf{z}} = 1$ $\hat{\mathbf{r}}\cdot\hat{\boldsymbol{\phi}} = \hat{\boldsymbol{\phi}}\cdot\hat{\mathbf{z}} = \hat{\mathbf{z}}\cdot\hat{\mathbf{r}} = 0$ $\hat{\mathbf{r}}\times\hat{\boldsymbol{\phi}} = \hat{\mathbf{z}}$ $\hat{\boldsymbol{\phi}}\times\hat{\mathbf{z}} = \hat{\mathbf{r}}$ $\hat{\mathbf{z}}\times\hat{\mathbf{r}} = \hat{\boldsymbol{\phi}}$	$\hat{\mathbf{R}}\cdot\hat{\mathbf{R}} = \hat{\boldsymbol{\theta}}\cdot\hat{\boldsymbol{\theta}} = \hat{\boldsymbol{\phi}}\cdot\hat{\boldsymbol{\phi}} = 1$ $\hat{\mathbf{R}}\cdot\hat{\boldsymbol{\theta}} = \hat{\boldsymbol{\theta}}\cdot\hat{\boldsymbol{\phi}} = \hat{\boldsymbol{\phi}}\cdot\hat{\mathbf{R}} = 0$ $\hat{\mathbf{R}}\times\hat{\boldsymbol{\theta}} = \hat{\boldsymbol{\phi}}$ $\hat{\boldsymbol{\theta}}\times\hat{\boldsymbol{\phi}} = \hat{\mathbf{R}}$ $\hat{\boldsymbol{\phi}}\times\hat{\mathbf{R}} = \hat{\boldsymbol{\theta}}$
Dot product $\quad \mathbf{A}\cdot\mathbf{B} =$	$A_xB_x + A_yB_y + A_zB_z$	$A_rB_r + A_\phi B_\phi + A_zB_z$	$A_RB_R + A_\theta B_\theta + A_\phi B_\phi$
Cross product $\quad \mathbf{A}\times\mathbf{B} =$	$\begin{vmatrix} \hat{\mathbf{x}} & \hat{\mathbf{y}} & \hat{\mathbf{z}} \\ A_x & A_y & A_z \\ B_x & B_y & B_z \end{vmatrix}$	$\begin{vmatrix} \hat{\mathbf{r}} & \hat{\boldsymbol{\phi}} & \hat{\mathbf{z}} \\ A_r & A_\phi & A_z \\ B_r & B_\phi & B_z \end{vmatrix}$	$\begin{vmatrix} \hat{\mathbf{R}} & \hat{\boldsymbol{\theta}} & \hat{\boldsymbol{\phi}} \\ A_R & A_\theta & A_\phi \\ B_R & B_\theta & B_\phi \end{vmatrix}$
Differential length $\quad d\mathbf{l} =$	$\hat{\mathbf{x}}\,dx + \hat{\mathbf{y}}\,dy + \hat{\mathbf{z}}\,dz$	$\hat{\mathbf{r}}\,dr + \hat{\boldsymbol{\phi}}r\,d\phi + \hat{\mathbf{z}}\,dz$	$\hat{\mathbf{R}}\,dR + \hat{\boldsymbol{\theta}}R\,d\theta + \hat{\boldsymbol{\phi}}R\sin\theta\,d\phi$
Differential surface areas	$d\mathbf{s}_x = \hat{\mathbf{x}}\,dy\,dz$ $d\mathbf{s}_y = \hat{\mathbf{y}}\,dx\,dz$ $d\mathbf{s}_z = \hat{\mathbf{z}}\,dx\,dy$	$d\mathbf{s}_r = \hat{\mathbf{r}}r\,d\phi\,dz$ $d\mathbf{s}_\phi = \hat{\boldsymbol{\phi}}\,dr\,dz$ $d\mathbf{s}_z = \hat{\mathbf{z}}r\,dr\,d\phi$	$d\mathbf{s}_R = \hat{\mathbf{R}}R^2\sin\theta\,d\theta\,d\phi$ $d\mathbf{s}_\theta = \hat{\boldsymbol{\theta}}R\sin\theta\,dR\,d\phi$ $d\mathbf{s}_\phi = \hat{\boldsymbol{\phi}}R\,dR\,d\theta$
Differential volume $dV =$	$dx\,dy\,dz$	$r\,dr\,d\phi\,dz$	$R^2\sin\theta\,dR\,d\theta\,d\phi$

Cylindrical Coordinate System

The base unit vectors obey the following right-hand cyclic relations:

$$\hat{\mathbf{r}} \times \hat{\boldsymbol{\phi}} = \hat{\mathbf{z}}, \qquad \hat{\boldsymbol{\phi}} \times \hat{\mathbf{z}} = \hat{\mathbf{r}}, \qquad \hat{\mathbf{z}} \times \hat{\mathbf{r}} = \hat{\boldsymbol{\phi}}, \qquad (3.37)$$

$$\mathbf{A} = \hat{\mathbf{a}}|\mathbf{A}| = \hat{\mathbf{r}}A_r + \hat{\boldsymbol{\phi}}A_\phi + \hat{\mathbf{z}}A_z, \qquad (3.38)$$

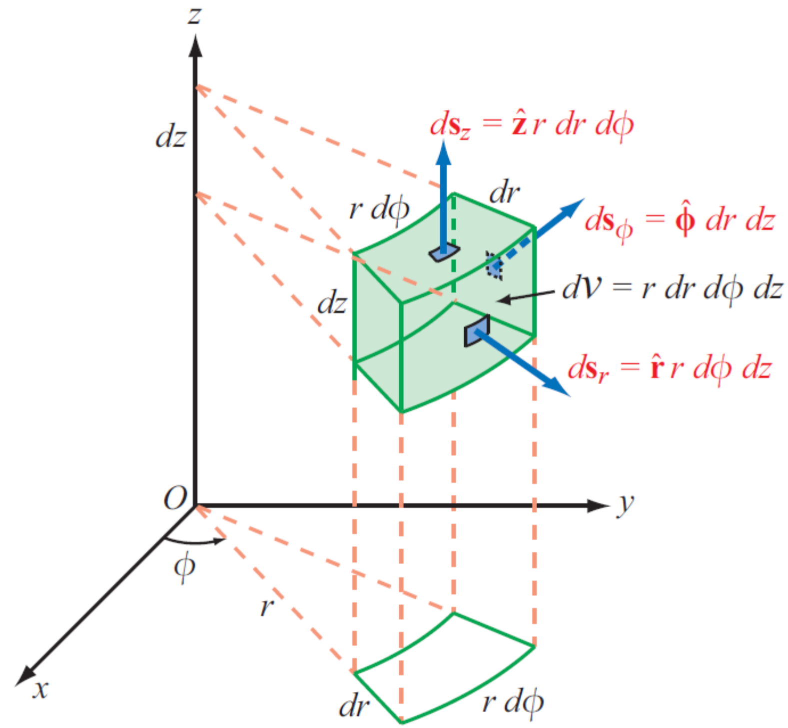


Figure 3-10: Differential areas and volume in cylindrical coordinates.

Example 3-3: Distance Vector in Cylindrical Coordinates

Find an expression for the unit vector of vector **A** shown in Fig. 3-11 in cylindrical coordinates.

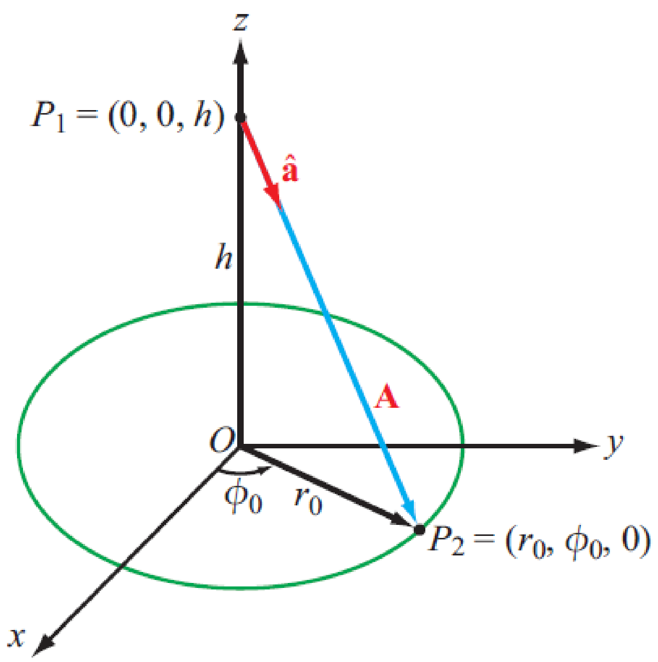


Figure 3-11: Geometry of Example 3-3.

Example 3-3: Distance Vector in Cylindrical Coordinates

Find an expression for the unit vector of vector **A** shown in Fig. 3-11 in cylindrical coordinates.

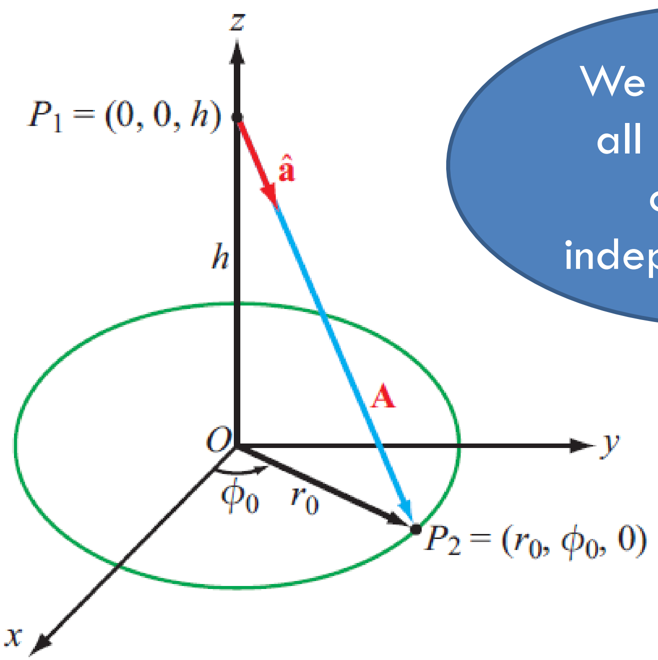


Figure 3-11: Geometry of Example 3-3.

Solution: In triangle OP_1P_2,

We assume A is all around the circle → independent of ϕ

$$\mathbf{A} = \overrightarrow{OP_2} - \overrightarrow{OP_1} = \hat{\mathbf{r}}r_0 - \hat{\mathbf{z}}h,$$

and

$$\hat{\mathbf{a}} = \frac{\mathbf{A}}{|\mathbf{A}|} = \frac{\hat{\mathbf{r}}r_0 - \hat{\mathbf{z}}h}{\sqrt{r_0^2 + h^2}}.$$

Independent of ϕ.

Example 3-4: Cylindrical Area

Find the area of a cylindrical surface described by $r = 5$, $30° \leq \phi \leq 60°$, and $0 \leq z \leq 3$ (Fig. 3-12).

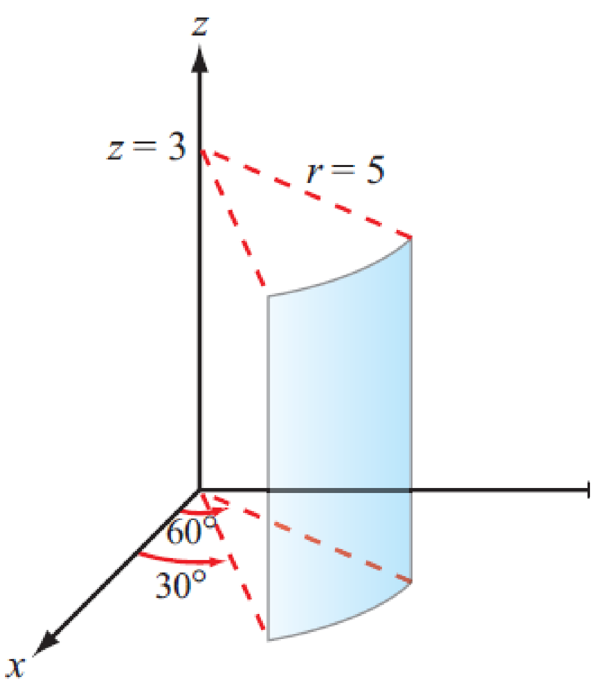


Figure 3-12: Cylindrical surface of Examp

Notes!

Example 3-4: Cylindrical Area

Differential surface areas

$$ds_x = \hat{\mathbf{x}}\, dy\, dz \qquad ds_r = \hat{\mathbf{r}} r\, d\phi\, dz$$
$$ds_y = \hat{\mathbf{y}}\, dx\, dz \qquad ds_\phi = \hat{\boldsymbol{\phi}}\, dr\, dz$$
$$ds_z = \hat{\mathbf{z}}\, dx\, dy \qquad ds_z = \hat{\mathbf{z}} r\, dr\, d\phi$$

Find the area of a cylindrical surface described by $r = 5$, $30° \le \phi \le 60°$, and $0 \le z \le 3$ (Fig. 3-12).

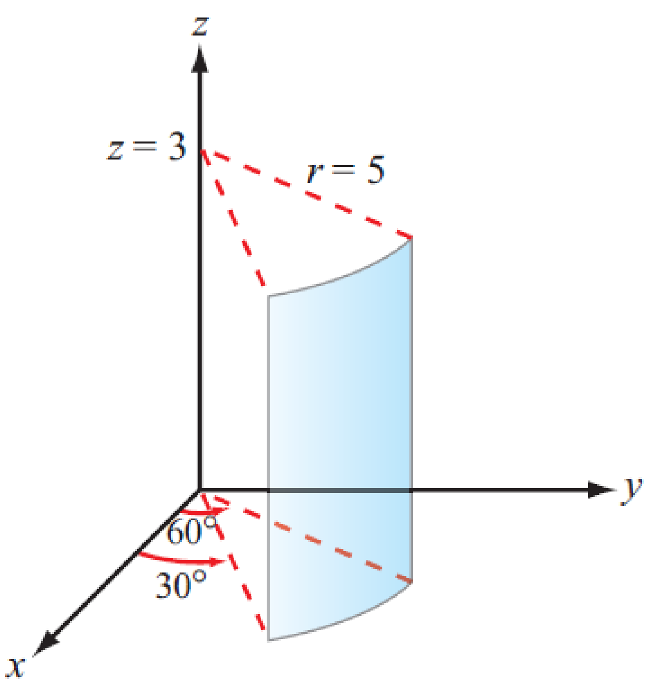


Figure 3-12: Cylindrical surface of Example 3-4.

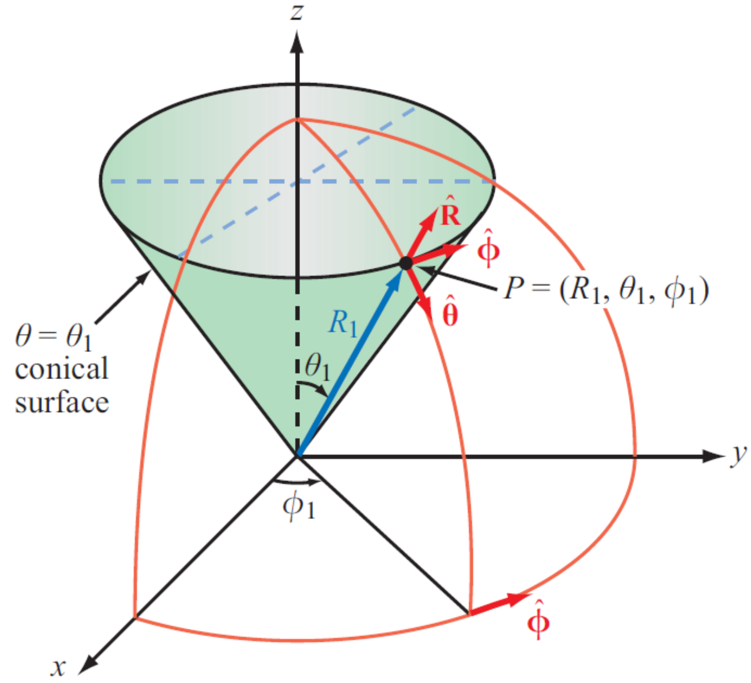
Solution: The prescribed surface is shown in Fig. 3-12. Use of Eq. (3.43a) for a surface element with constant r gives

$$S = r \int_{\phi=30°}^{60°} d\phi \int_{z=0}^{3} dz = 5\phi \Big|_{\pi/6}^{\pi/3} z\Big|_0^3 = \frac{5\pi}{2}.$$

Note that ϕ had to be converted to [...]s before evaluating the integration limits.

Note that we use
dsr = r dϕ dz

Spherical Coordinate System



$$\hat{\mathbf{R}} \times \hat{\boldsymbol{\theta}} = \hat{\boldsymbol{\phi}}, \quad \hat{\boldsymbol{\theta}} \times \hat{\boldsymbol{\phi}} = \hat{\mathbf{R}}, \quad \hat{\boldsymbol{\phi}} \times \hat{\mathbf{R}} = \hat{\boldsymbol{\theta}}. \qquad (3.45)$$

A vector with components A_R, A_θ, and A_ϕ is written as

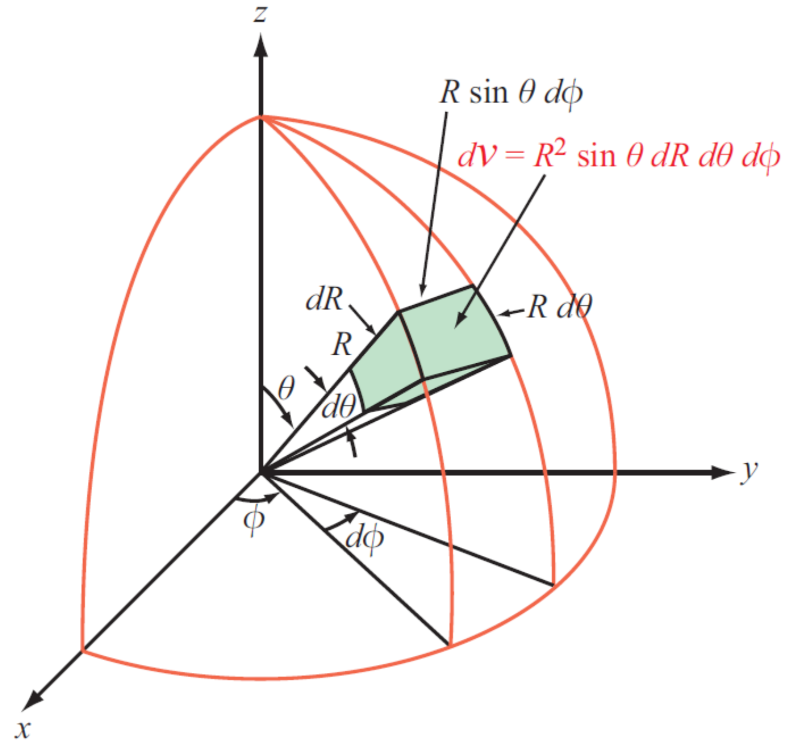
$$\mathbf{A} = \hat{\mathbf{a}}|\mathbf{A}| = \hat{\mathbf{R}}A_R + \hat{\boldsymbol{\theta}}A_\theta + \hat{\boldsymbol{\phi}}A_\phi, \qquad (3.46)$$

and its magnitude is

$$|\mathbf{A}| = \sqrt[+]{\mathbf{A}\cdot\mathbf{A}} = \sqrt[+]{A_R^2 + A_\theta^2 + A_\phi^2}. \qquad (3.47)$$

The position vector of point $P = (R_1, \theta_1, \phi_1)$ is simply

$$\mathbf{R}_1 = \overrightarrow{OP} = \hat{\mathbf{R}}R_1, \qquad (3.48)$$



Example 3-6: Charge in a Sphere

A sphere of radius 2 cm contains a volume charge density ρ_v given by

$$\rho_v = 4\cos^2\theta \qquad (\mathrm{C/m^3}).$$

Find the total charge Q contained in the sphere.

Notes!

Differential volume $dV =$	$dx\,dy\,dz$	$r\,dr\,d\phi\,dz$	$R^2 \sin\theta\,dR\,d\theta\,d\phi$

A sphere of radius 2 cm contains a volume charge density ρ_v given by

$$\rho_v = 4\cos^2\theta \qquad (\text{C/m}^3).$$

Find the total charge Q contained in the sphere.

Solution:

$$Q = \int_V \rho_v \, dV$$

$$= \int_{\phi=0}^{2\pi} \int_{\theta=0}^{\pi} \int_{R=0}^{2\times10^{-2}} (4\cos^2\theta) R^2 \sin\theta \, dR \, d\theta \, d\phi$$

$$= 4 \int_0^{2\pi} \int_0^{\pi} \left(\frac{R^3}{3}\right)\Bigg|_0^{2\times10^{-2}} \sin\theta \cos^2\theta \, d\theta \, d\phi$$

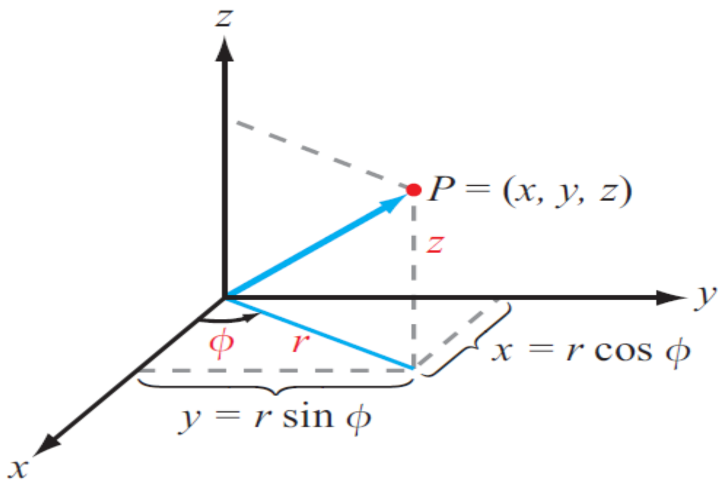
$$= \frac{32}{3} \times 10^{-6} \int_0^{2\pi} \left(-\frac{\cos^3\theta}{3}\right)\Bigg|_0^{\pi} d\phi$$

$$= \frac{64}{9} \times 10^{-6} \int_0^{2\pi} d\phi$$

$$= \frac{128\pi}{9} \times 10^{-6} = 44.68 \qquad (\mu\text{C}).$$

Coordinate Transformations: Coordinates

- To solve a problem, we select the coordinate system that best fits its geometry
- Sometimes we need to transform between coordinate systems
  - Transforming a point
  - Transforming a vector coordinates



$$r = \sqrt[+]{x^2 + y^2}, \qquad \phi = \tan^{-1}\left(\frac{y}{x}\right),$$

and the inverse relations are

$$x = r\cos\phi, \qquad y = r\sin\phi.$$

Table 3-2: Coordinate transformation relations.

Transformation	Coordinate Variables	Unit Vectors	Vector Components
Cartesian to cylindrical	$r = \sqrt[+]{x^2 + y^2}$ $\phi = \tan^{-1}(y/x)$ $z = z$	$\hat{\mathbf{r}} = \hat{\mathbf{x}} \cos\phi + \hat{\mathbf{y}} \sin\phi$ $\hat{\boldsymbol{\phi}} = -\hat{\mathbf{x}} \sin\phi + \hat{\mathbf{y}} \cos\phi$ $\hat{\mathbf{z}} = \hat{\mathbf{z}}$	$A_r = A_x \cos\phi + A_y \sin\phi$ $A_\phi = -A_x \sin\phi + A_y \cos\phi$ $A_z = A_z$
Cylindrical to Cartesian	$x = r\cos\phi$ $y = r\sin\phi$ $z = z$	$\hat{\mathbf{x}} = \hat{\mathbf{r}} \cos\phi - \hat{\boldsymbol{\phi}} \sin\phi$ $\hat{\mathbf{y}} = \hat{\mathbf{r}} \sin\phi + \hat{\boldsymbol{\phi}} \cos\phi$ $\hat{\mathbf{z}} = \hat{\mathbf{z}}$	$A_x = A_r \cos\phi - A_\phi \sin\phi$ $A_y = A_r \sin\phi + A_\phi \cos\phi$ $A_z = A_z$
Cartesian to spherical	$R = \sqrt[+]{x^2 + y^2 + z^2}$ $\theta = \tan^{-1}[\sqrt[+]{x^2 + y^2}/z]$ $\phi = \tan^{-1}(y/x)$	$\hat{\mathbf{R}} = \hat{\mathbf{x}} \sin\theta \cos\phi + \hat{\mathbf{y}} \sin\theta \sin\phi + \hat{\mathbf{z}} \cos\theta$ $\hat{\boldsymbol{\theta}} = \hat{\mathbf{x}} \cos\theta \cos\phi + \hat{\mathbf{y}} \cos\theta \sin\phi - \hat{\mathbf{z}} \sin\theta$ $\hat{\boldsymbol{\phi}} = -\hat{\mathbf{x}} \sin\phi + \hat{\mathbf{y}} \cos\phi$	$A_R = A_x \sin\theta \cos\phi + A_y \sin\theta \sin\phi + A_z \cos\theta$ $A_\theta = A_x \cos\theta \cos\phi + A_y \cos\theta \sin\phi - A_z \sin\theta$ $A_\phi = -A_x \sin\phi + A_y \cos\phi$
Spherical to Cartesian	$x = R\sin\theta\cos\phi$ $y = R\sin\theta\sin\phi$ $z = R\cos\theta$	$\hat{\mathbf{x}} = \hat{\mathbf{R}} \sin\theta \cos\phi + \hat{\boldsymbol{\theta}} \cos\theta \cos\phi - \hat{\boldsymbol{\phi}} \sin\phi$ $\hat{\mathbf{y}} = \hat{\mathbf{R}} \sin\theta \sin\phi + \hat{\boldsymbol{\theta}} \cos\theta \sin\phi + \hat{\boldsymbol{\phi}} \cos\phi$ $\hat{\mathbf{z}} = \hat{\mathbf{R}} \cos\theta - \hat{\boldsymbol{\theta}} \sin\theta$	$A_x = A_R \sin\theta \cos\phi + A_\theta \cos\theta \cos\phi - A_\phi \sin\phi$ $A_y = A_R \sin\theta \sin\phi + A_\theta \cos\theta \sin\phi + A_\phi \cos\phi$ $A_z = A_R \cos\theta - A_\theta \sin\theta$
Cylindrical to spherical	$R = \sqrt[+]{r^2 + z^2}$ $\theta = \tan^{-1}(r/z)$ $\phi = \phi$	$\hat{\mathbf{R}} = \hat{\mathbf{r}} \sin\theta + \hat{\mathbf{z}} \cos\theta$ $\hat{\boldsymbol{\theta}} = \hat{\mathbf{r}} \cos\theta - \hat{\mathbf{z}} \sin\theta$ $\hat{\boldsymbol{\phi}} = \hat{\boldsymbol{\phi}}$	$A_R = A_r \sin\theta + A_z \cos\theta$ $A_\theta = A_r \cos\theta - A_z \sin\theta$ $A_\phi = A_\phi$
Spherical to cylindrical	$r = R\sin\theta$ $\phi = \phi$ $z = R\cos\theta$	$\hat{\mathbf{r}} = \hat{\mathbf{R}} \sin\theta + \hat{\boldsymbol{\theta}} \cos\theta$ $\hat{\boldsymbol{\phi}} = \hat{\boldsymbol{\phi}}$ $\hat{\mathbf{z}} = \hat{\mathbf{R}} \cos\theta - \hat{\boldsymbol{\theta}} \sin\theta$	$A_r = A_R \sin\theta + A_\theta \cos\theta$ $A_\phi = A_\phi$ $A_z = A_R \cos\theta - A_\theta \sin\theta$

Example

Given point $P_1 = (3, -4, 3)$ and vector $\mathbf{A} = \hat{\mathbf{x}}2 - \hat{\mathbf{y}}3 + \hat{\mathbf{z}}4$, defined in Cartesian coordinates, express P_1 and $\mathbf{A}$ in cylindrical coordinates and evaluate $\mathbf{A}$ at P_1.

We have a point and a vector!

Table 3-2: Coordinate transformation relations.

Transformation	Coordinate Variables	Unit Vectors	Vector Components
Cartesian to cylindrical	$r = \sqrt[+]{x^2 + y^2}$ $\phi = \tan^{-1}(y/x)$ $z = z$	$\hat{\mathbf{r}} = \hat{\mathbf{x}} \cos\phi + \hat{\mathbf{y}} \sin\phi$ $\hat{\boldsymbol{\phi}} = -\hat{\mathbf{x}} \sin\phi + \hat{\mathbf{y}} \cos\phi$ $\hat{\mathbf{z}} = \hat{\mathbf{z}}$	$A_r = A_x \cos\phi + A_y \sin\phi$ $A_\phi = -A_x \sin\phi + A_y \cos\phi$ $A_z = A_z$
Cylindrical to Cartesian	$x = r\cos\phi$ $y = r\sin\phi$ $z = z$	$\hat{\mathbf{x}} = \hat{\mathbf{r}} \cos\phi - \hat{\boldsymbol{\phi}} \sin\phi$ $\hat{\mathbf{y}} = \hat{\mathbf{r}} \sin\phi + \hat{\boldsymbol{\phi}} \cos\phi$ $\hat{\mathbf{z}} = \hat{\mathbf{z}}$	$A_x = A_r \cos\phi - A_\phi \sin\phi$ $A_y = A_r \sin\phi + A_\phi \cos\phi$ $A_z = A_z$
Cartesian to spherical	$R = \sqrt[+]{x^2 + y^2 + z^2}$ $\theta = \tan^{-1}[\sqrt[+]{x^2 + y^2}/z]$ $\phi = \tan^{-1}(y/x)$	$\hat{\mathbf{R}} = \hat{\mathbf{x}} \sin\theta\cos\phi + \hat{\mathbf{y}} \sin\theta\sin\phi + \hat{\mathbf{z}} \cos\theta$ $\hat{\boldsymbol{\theta}} = \hat{\mathbf{x}} \cos\theta\cos\phi + \hat{\mathbf{y}} \cos\theta\sin\phi - \hat{\mathbf{z}} \sin\theta$ $\hat{\boldsymbol{\phi}} = -\hat{\mathbf{x}} \sin\phi + \hat{\mathbf{y}} \cos\phi$	$A_R = A_x \sin\theta\cos\phi + A_y \sin\theta\sin\phi + A_z \cos\theta$ $A_\theta = A_x \cos\theta\cos\phi + A_y \cos\theta\sin\phi - A_z \sin\theta$ $A_\phi = -A_x \sin\phi + A_y \cos\phi$
Spherical to Cartesian	$x = R\sin\theta\cos\phi$ $y = R\sin\theta\sin\phi$ $z = R\cos\theta$	$\hat{\mathbf{x}} = \hat{\mathbf{R}} \sin\theta\cos\phi + \hat{\boldsymbol{\theta}} \cos\theta\cos\phi - \hat{\boldsymbol{\phi}} \sin\phi$ $\hat{\mathbf{y}} = \hat{\mathbf{R}} \sin\theta\sin\phi + \hat{\boldsymbol{\theta}} \cos\theta\sin\phi + \hat{\boldsymbol{\phi}} \cos\phi$ $\hat{\mathbf{z}} = \hat{\mathbf{R}} \cos\theta - \hat{\boldsymbol{\theta}} \sin\theta$	$A_x = A_R \sin\theta\cos\phi + A_\theta \cos\theta\cos\phi - A_\phi \sin\phi$ $A_y = A_R \sin\theta\sin\phi + A_\theta \cos\theta\sin\phi + A_\phi \cos\phi$ $A_z = A_R \cos\theta - A_\theta \sin\theta$
Cylindrical to spherical	$R = \sqrt[+]{r^2 + z^2}$ $\theta = \tan^{-1}(r/z)$ $\phi = \phi$	$\hat{\mathbf{R}} = \hat{\mathbf{r}} \sin\theta + \hat{\mathbf{z}} \cos\theta$ $\hat{\boldsymbol{\theta}} = \hat{\mathbf{r}} \cos\theta - \hat{\mathbf{z}} \sin\theta$ $\hat{\boldsymbol{\phi}} = \hat{\boldsymbol{\phi}}$	$A_R = A_r \sin\theta + A_z \cos\theta$ $A_\theta = A_r \cos\theta - A_z \sin\theta$ $A_\phi = A_\phi$
Spherical to cylindrical	$r = R\sin\theta$ $\phi = \phi$ $z = R\cos\theta$	$\hat{\mathbf{r}} = \hat{\mathbf{R}} \sin\theta + \hat{\boldsymbol{\theta}} \cos\theta$ $\hat{\boldsymbol{\phi}} = \hat{\boldsymbol{\phi}}$ $\hat{\mathbf{z}} = \hat{\mathbf{R}} \cos\theta - \hat{\boldsymbol{\theta}} \sin\theta$	$A_r = A_R \sin\theta + A_\theta \cos\theta$ $A_\phi = A_\phi$ $A_z = A_R \cos\theta - A_\theta \sin\theta$

Example

Given point $P_1 = (3, -4, 3)$ and vector $\mathbf{A} = \hat{\mathbf{x}}2 - \hat{\mathbf{y}}3 + \hat{\mathbf{z}}4$, defined in Cartesian coordinates, express P_1 and $\mathbf{A}$ in cylindrical coordinates and evaluate $\mathbf{A}$ at P_1.

Solution: For point P_1, $x = 3$, $y = -4$, and $z = 3$. Using Eq. (3.51), we have

$$r = \sqrt[+]{x^2 + y^2} = 5, \quad \phi = \tan^{-1}\frac{y}{x} = -53.1^\circ = 306.9^\circ,$$

and z remains unchanged. Hence, $P_1 = (5, 306.9^\circ, 3)$ in cylindrical coordinates.

The cylindrical components of vector $\mathbf{A} = \hat{\mathbf{r}}A_r + \hat{\boldsymbol{\phi}}A_\phi + \hat{\mathbf{z}}A_z$ can be determined by applying Eqs. (3.58a) and (3.58b):

$$A_r = A_x \cos\phi + A_y \sin\phi = 2\cos\phi - 3\sin\phi,$$

$$A_\phi = -A_x \sin\phi + A_y \cos\phi = -2\sin\phi - 3\cos\phi,$$

$$A_z = 4.$$

Hence,

$$\mathbf{A} = \hat{\mathbf{r}}(2\cos\phi - 3\sin\phi) - \hat{\boldsymbol{\phi}}(2\sin\phi + 3\cos\phi) + \hat{\mathbf{z}}4.$$

At point P, $\phi = 306.9^\circ$, which gives

$$\mathbf{A} = \hat{\mathbf{r}}3.60 - \hat{\boldsymbol{\phi}}0.20 + \hat{\mathbf{z}}4.$$

Another example:

- Convert from cylindrical to spherical

Cylindrical to spherical	$R = \sqrt[+]{r^2 + z^2}$ $\theta = \tan^{-1}(r/z)$ $\phi = \phi$

Next….

Gradient of A Scalar Field

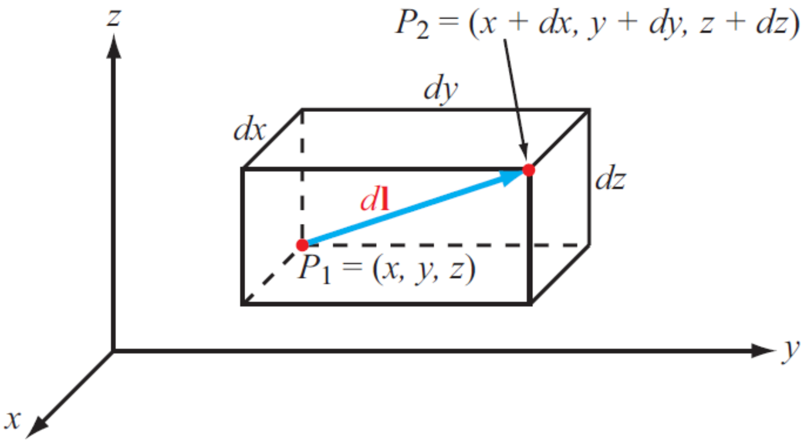


Figure 3-19: Differential distance vector $d\mathbf{l}$ between points P_1 and P_2.

From differential calculus, the temperature difference between points P_1 and P_2, $dT = T_2 - T_1$, is

$$dT = \frac{\partial T}{\partial x}\,dx + \frac{\partial T}{\partial y}\,dy + \frac{\partial T}{\partial z}\,dz. \qquad (3.70)$$

Because $dx = \hat{\mathbf{x}} \cdot d\mathbf{l}$, $dy = \hat{\mathbf{y}} \cdot d\mathbf{l}$, and $dz = \hat{\mathbf{z}} \cdot d\mathbf{l}$, Eq. (3.70) can be rewritten as

$$\begin{aligned} dT &= \hat{\mathbf{x}}\frac{\partial T}{\partial x} \cdot d\mathbf{l} + \hat{\mathbf{y}}\frac{\partial T}{\partial y} \cdot d\mathbf{l} + \hat{\mathbf{z}}\frac{\partial T}{\partial z} \cdot d\mathbf{l} \\ &= \left[\hat{\mathbf{x}}\frac{\partial T}{\partial x} + \hat{\mathbf{y}}\frac{\partial T}{\partial y} + \hat{\mathbf{z}}\frac{\partial T}{\partial z}\right] \cdot d\mathbf{l}. \end{aligned} \qquad (3.71)$$

$$\nabla T = \text{grad } T = \hat{\mathbf{x}}\frac{\partial T}{\partial x} + \hat{\mathbf{y}}\frac{\partial T}{\partial y} + \hat{\mathbf{z}}\frac{\partial T}{\partial z}\,. \qquad (3.72)$$

Equation (3.71) can then be expressed as

$$dT = \nabla T \cdot d\mathbf{l}. \qquad (3.73)$$

The symbol ∇ is called the ***del*** or ***gradient operator*** and is defined as

$$\nabla = \hat{\mathbf{x}}\frac{\partial}{\partial x} + \hat{\mathbf{y}}\frac{\partial}{\partial y} + \hat{\mathbf{z}}\frac{\partial}{\partial z} \qquad \text{(Cartesian)}. \qquad (3.74)$$

Gradient (cont.)

With $d\mathbf{l} = \hat{\mathbf{a}}_l \, dl$, where $\hat{\mathbf{a}}_l$ is the unit vector of $d\mathbf{l}$, the ***directional derivative*** of T along $\hat{\mathbf{a}}_l$ is

$$\frac{dT}{dl} = \nabla T \cdot \hat{\mathbf{a}}_l. \qquad (3.75)$$

We can find the difference $(T_2 - T_1)$, where $T_1 = T(x_1, y_1, z_1)$ and $T_2 = T(x_2, y_2, z_2)$ are the values of T at points $P_1 = (x_1, y_1, z_1)$ and $P_2 = (x_2, y_2, z_2)$ not necessarily infinitesimally close to one another, by integrating both sides of Eq. (3.73). Thus,

$$T_2 - T_1 = \int_{P_1}^{P_2} \nabla T \cdot d\mathbf{l}. \qquad (3.76)$$

Example 3-9: Directional Derivative

Find the directional derivative of $T = x^2 + y^2 z$ along direction $\hat{\mathbf{x}}2 + \hat{\mathbf{y}}3 - \hat{\mathbf{z}}2$ and evaluate it at $(1, -1, 2)$.

Solution: First, we find the gradient of T:

$$\nabla T = \left(\hat{\mathbf{x}}\frac{\partial}{\partial x} + \hat{\mathbf{y}}\frac{\partial}{\partial y} + \hat{\mathbf{z}}\frac{\partial}{\partial z}\right)(x^2 + y^2 z)$$

$$= \hat{\mathbf{x}}2x + \hat{\mathbf{y}}2yz + \hat{\mathbf{z}}y^2.$$

We denote $\mathbf{l}$ as the given direction,

$$\mathbf{l} = \hat{\mathbf{x}}2 + \hat{\mathbf{y}}3 - \hat{\mathbf{z}}2.$$

Its unit vector is

$$\hat{\mathbf{a}}_l = \frac{\mathbf{l}}{|\mathbf{l}|} = \frac{\hat{\mathbf{x}}2 + \hat{\mathbf{y}}3 - \hat{\mathbf{z}}2}{\sqrt{2^2 + 3^2 + 2^2}} = \frac{\hat{\mathbf{x}}2 + \hat{\mathbf{y}}3 - \hat{\mathbf{z}}2}{\sqrt{17}} .$$

Application of Eq. (3.75) gives

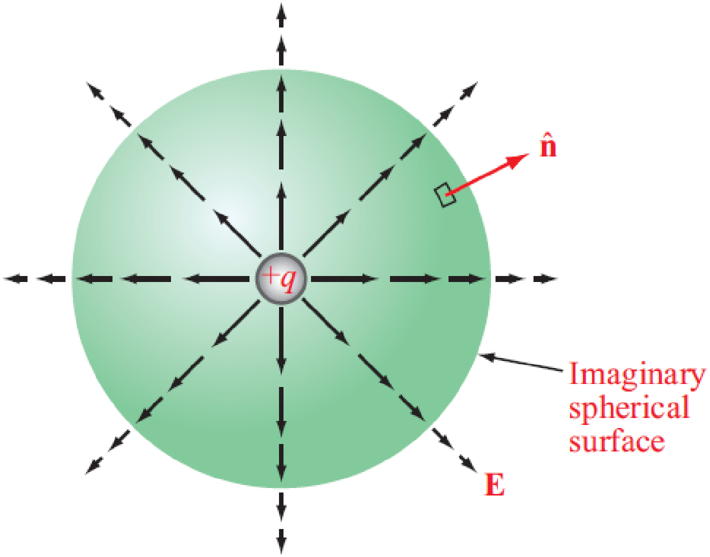
$$\frac{dT}{dl} = \nabla T \cdot \hat{\mathbf{a}}_l = (\hat{\mathbf{x}}2x + \hat{\mathbf{y}}2yz + \hat{\mathbf{z}}y^2) \cdot \left(\frac{\hat{\mathbf{x}}2 + \hat{\mathbf{y}}3 - \hat{\mathbf{z}}2}{\sqrt{17}}\right)$$

$$= \frac{4x + 6yz - 2y^2}{\sqrt{17}} .$$

At $(1, -1, 2)$,

$$\left.\frac{dT}{dl}\right|_{(1,-1,2)} = \frac{4 - 12 - 2}{\sqrt{17}} = \frac{-10}{\sqrt{17}} .$$

Divergence of a Vector Field



Divergence Theorem

$$\int_{V} \nabla \cdot \mathbf{E}\, dV = \oint_{S} \mathbf{E} \cdot d\mathbf{s} \qquad \text{(divergence theorem).} \tag{3.98}$$

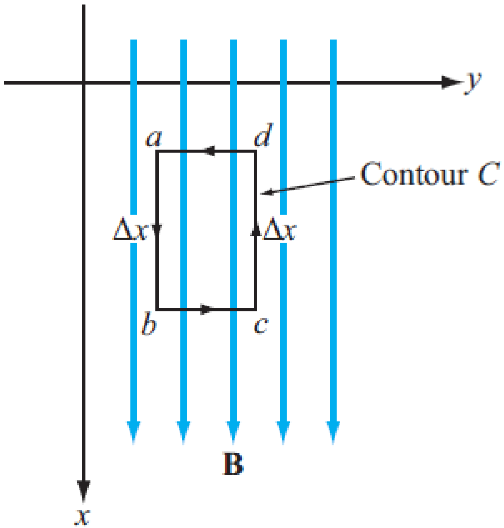
Useful tool for converting integration over a volume to one over the surface enclosing that volume, and vice versa

Curl of a Vector Field

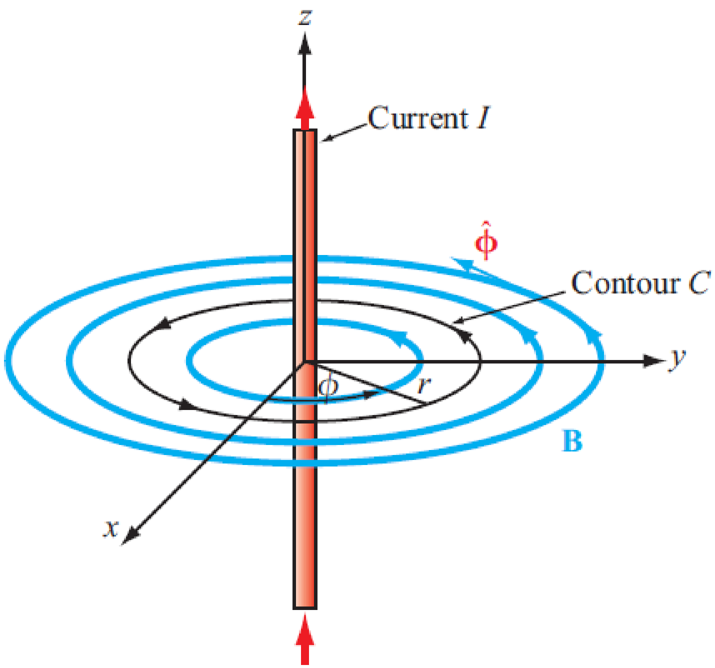
$$\text{Circulation} = \oint_C \mathbf{B} \cdot d\mathbf{l}.$$

$$\nabla \times \mathbf{B} = \text{curl } \mathbf{B} = \lim_{\Delta s \to 0} \frac{1}{\Delta s} \left[\hat{\mathbf{n}} \oint_C \mathbf{B} \cdot d\mathbf{l} \right]_{\max} . \quad (3.103)$$

*Thus, curl **B** is the circulation of **B** per unit area, with the area Δs of the contour C being oriented such that the circulation is maximum.*



(a) Uniform field



(b) Azimuthal field

Figure 3-22: Circulation is zero for the uniform field in (a), but it is not zero for the azimuthal field in (b).

Stokes's Theorem

***Stokes's theorem** converts the surface integral of the curl of a vector over an open surface S into a line integral of the vector along the contour C bounding the surface S.*

For the geometry shown in Fig. 3-23, ***Stokes's theorem*** states

$$\int_S (\nabla \times \mathbf{B}) \cdot d\mathbf{s} = \oint_C \mathbf{B} \cdot d\mathbf{l} \qquad \text{(Stokes's theorem)}, \tag{3.107}$$

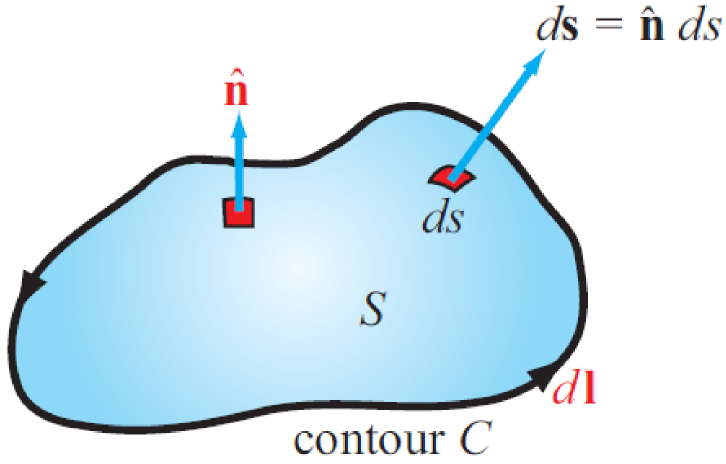


Figure 3-23: The direction of the unit vector $\hat{\mathbf{n}}$ is along the thumb when the other four fingers of the right hand follow $d\mathbf{l}$.

Laplacian Operator

Laplacian of a Scalar Field

$$\nabla^2 V = \nabla \cdot (\nabla V) = \frac{\partial^2 V}{\partial x^2} + \frac{\partial^2 V}{\partial y^2} + \frac{\partial^2 V}{\partial z^2} . \qquad (3.110)$$

Laplacian of a Vector Field

$$\nabla^2 \mathbf{E} = \left(\frac{\partial^2}{\partial x^2} + \frac{\partial^2}{\partial y^2} + \frac{\partial^2}{\partial z^2} \right) \mathbf{E}$$

$$= \hat{\mathbf{x}}\, \nabla^2 E_x + \hat{\mathbf{y}}\, \nabla^2 E_y + \hat{\mathbf{z}}\, \nabla^2 E_z$$

Useful Relation

$$\nabla^2 \mathbf{E} = \nabla(\nabla \cdot \mathbf{E}) - \nabla \times (\nabla \times \mathbf{E}). \qquad (3.113)$$