$$\mathbf{A}\times\mathbf{B} = \begin{vmatrix} \hat{\mathbf{x}} & \hat{\mathbf{y}} & \hat{\mathbf{z}} \\ -1 & 2 & 0 \\ -1 & 0 & 3 \end{vmatrix} = 6\,\hat{\mathbf{x}} + 3\,\hat{\mathbf{y}} + 2\,\hat{\mathbf{z}}.$$

This has the right *direction*, but the wrong *magnitude*. To make a *unit* vector out of it, simply divide by its length:

$$|\mathbf{A}\times\mathbf{B}| = \sqrt{36+9+4} = 7. \qquad \hat{\mathbf{n}} = \frac{\mathbf{A}\times\mathbf{B}}{|\mathbf{A}\times\mathbf{B}|} = \boxed{\tfrac{6}{7}\hat{\mathbf{x}} + \tfrac{3}{7}\hat{\mathbf{y}} + \tfrac{2}{7}\hat{\mathbf{z}}}.$$

Problem 1.5

$$\mathbf{A}\times(\mathbf{B}\times\mathbf{C}) = \begin{vmatrix} \hat{\mathbf{x}} & \hat{\mathbf{y}} & \hat{\mathbf{z}} \\ A_x & A_y & A_z \\ (B_yC_z - B_zC_y) & (B_zC_x - B_xC_z) & (B_xC_y - B_yC_x) \end{vmatrix}$$

$$= \hat{\mathbf{x}}[A_y(B_xC_y - B_yC_x) - A_z(B_zC_x - B_xC_z)] + \hat{\mathbf{y}}() + \hat{\mathbf{z}}()$$

(I'll just check the x-component; the others go the same way.)

$$= \hat{\mathbf{x}}(A_yB_xC_y - A_yB_yC_x - A_zB_zC_x + A_zB_xC_z) + \hat{\mathbf{y}}() + \hat{\mathbf{z}}().$$

$$\mathbf{B}(\mathbf{A}\cdot\mathbf{C}) - \mathbf{C}(\mathbf{A}\cdot\mathbf{B}) = [B_x(A_xC_x + A_yC_y + A_zC_z) - C_x(A_xB_x + A_yB_y + A_zB_z)]\,\hat{\mathbf{x}} + ()\,\hat{\mathbf{y}} + ()\,\hat{\mathbf{z}}$$

$$= \hat{\mathbf{x}}(A_yB_xC_y + A_zB_xC_z - A_yB_yC_x - A_zB_zC_x) + \hat{\mathbf{y}}() + \hat{\mathbf{z}}().$$ They agree.

Problem 1.6

$$\mathbf{A}\times(\mathbf{B}\times\mathbf{C}) + \mathbf{B}\times(\mathbf{C}\times\mathbf{A}) + \mathbf{C}\times(\mathbf{A}\times\mathbf{B}) = \mathbf{B}(\mathbf{A}\cdot\mathbf{C}) - \mathbf{C}(\mathbf{A}\cdot\mathbf{B}) + \mathbf{C}(\mathbf{A}\cdot\mathbf{B}) - \mathbf{A}(\mathbf{C}\cdot\mathbf{B}) + \mathbf{A}(\mathbf{B}\cdot\mathbf{C}) - \mathbf{B}(\mathbf{C}\cdot\mathbf{A}) = 0.$$

So: $\mathbf{A}\times(\mathbf{B}\times\mathbf{C}) - (\mathbf{A}\times\mathbf{B})\times\mathbf{C} = -\mathbf{B}\times(\mathbf{C}\times\mathbf{A}) = \mathbf{A}(\mathbf{B}\cdot\mathbf{C}) - \mathbf{C}(\mathbf{A}\cdot\mathbf{B})$.

If this is zero, then either $\mathbf{A}$ is parallel to $\mathbf{C}$ (including the case in which they point in *opposite* directions, or one is zero), or else $\mathbf{B}\cdot\mathbf{C} = \mathbf{B}\cdot\mathbf{A} = 0$, in which case $\mathbf{B}$ is perpendicular to $\mathbf{A}$ and $\mathbf{C}$ (including the case $\mathbf{B} = 0$).

Conclusion: $\boxed{\mathbf{A}\times(\mathbf{B}\times\mathbf{C}) = (\mathbf{A}\times\mathbf{B})\times\mathbf{C} \iff \text{either } \mathbf{A} \text{ is parallel to } \mathbf{C}\text{, or } \mathbf{B} \text{ is perpendicular to } \mathbf{A} \text{ and } \mathbf{C}.}$

Problem 1.7

$$\boldsymbol{\mathscr{r}} = (4\,\hat{\mathbf{x}} + 6\,\hat{\mathbf{y}} + 8\,\hat{\mathbf{z}}) - (2\,\hat{\mathbf{x}} + 8\,\hat{\mathbf{y}} + 7\,\hat{\mathbf{z}}) = \boxed{2\,\hat{\mathbf{x}} - 2\,\hat{\mathbf{y}} + \hat{\mathbf{z}}}$$

$$\mathscr{r} = \sqrt{4+4+1} = \boxed{3}$$

$$\hat{\boldsymbol{\mathscr{r}}} = \frac{\boldsymbol{\mathscr{r}}}{\mathscr{r}} = \boxed{\tfrac{2}{3}\hat{\mathbf{x}} - \tfrac{2}{3}\hat{\mathbf{y}} + \tfrac{1}{3}\hat{\mathbf{z}}}$$

Problem 1.8

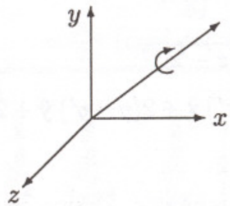
(a) $\bar{A}_y\bar{B}_y + \bar{A}_z\bar{B}_z = (\cos\phi A_y + \sin\phi A_z)(\cos\phi B_y + \sin\phi B_z) + (-\sin\phi A_y + \cos\phi A_z)(-\sin\phi B_y + \cos\phi B_z)$
$= \cos^2\phi A_yB_y + \sin\phi\cos\phi(A_yB_z + A_zB_y) + \sin^2\phi A_zB_z + \sin^2\phi A_yB_y - \sin\phi\cos\phi(A_yB_z + A_zB_y) + \cos^2\phi A_zB_z$
$= (\cos^2\phi + \sin^2\phi)A_yB_y + (\sin^2\phi + \cos^2\phi)A_zB_z = A_yB_y + A_zB_z.$ ✓

(b) $(\overline{A}_x)^2 + (\overline{A}_y)^2 + (\overline{A}_z)^2 = \Sigma_{i=1}^3 \overline{A}_i\overline{A}_i = \Sigma_{i=1}^3 \left(\Sigma_{j=1}^3 R_{ij}A_j\right)\left(\Sigma_{k=1}^3 R_{ik}A_k\right) = \Sigma_{j,k}\left(\Sigma_i R_{ij}R_{ik}\right)A_jA_k.$

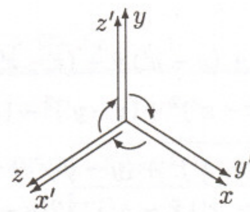
This equals $A_x^2 + A_y^2 + A_z^2$ *provided* $\boxed{\Sigma_{i=1}^3 R_{ij}R_{ik} = \begin{Bmatrix} 1 & if & j = k \\ 0 & if & j \neq k \end{Bmatrix}}$

Moreover, if R is to preserve lengths for *all* vectors $\mathbf{A}$, then this condition is not only *sufficient* but also *necessary*. For suppose $\mathbf{A} = (1,0,0)$. Then $\Sigma_{j,k}\left(\Sigma_i R_{ij}R_{ik}\right)A_jA_k = \Sigma_i R_{i1}R_{i1}$, and this must equal 1 (since we want $\overline{A}_x^2 + \overline{A}_y^2 + \overline{A}_z^2 = 1$). Likewise, $\Sigma_{i=1}^3 R_{i2}R_{i2} = \Sigma_{i=1}^3 R_{i3}R_{i3} = 1$. To check the case $j \neq k$, choose $\mathbf{A} = (1,1,0)$. Then we want $2 = \Sigma_{j,k}\left(\Sigma_i R_{ij}R_{ik}\right)A_jA_k = \Sigma_i R_{i1}R_{i1} + \Sigma_i R_{i2}R_{i2} + \Sigma_i R_{i1}R_{i2} + \Sigma_i R_{i2}R_{i1}$. But we already know that the first two sums are both 1; the third and fourth are *equal*, so $\Sigma_i R_{i1}R_{i2} = \Sigma_i R_{i2}R_{i1} = 0$, and so on for other unequal combinations of j, k. ✓ In matrix notation: $\tilde{R}R = 1$, where $\tilde{R}$ is the *transpose* of R.

Problem 1.9



Looking down the axis:



A 120° rotation carries the z axis into the y $(=\overline{z})$ axis, y into x $(=\overline{y})$, and x into z $(=\overline{x})$. So $\overline{A}_x = A_z$, $\overline{A}_y = A_x$, $\overline{A}_z = A_y$.

$$\boxed{R = \begin{pmatrix} 0 & 0 & 1 \\ 1 & 0 & 0 \\ 0 & 1 & 0 \end{pmatrix}}$$

Problem 1.10

(a) $\boxed{\text{No change.}}$ $(\overline{A}_x = A_x,\ \overline{A}_y = A_y,\ \overline{A}_z = A_z)$

(b) $\boxed{\mathbf{A} \longrightarrow -\mathbf{A},}$ in the sense $(\overline{A}_x = -A_x,\ \overline{A}_y = -A_y,\ \overline{A}_z = -A_z)$

(c) $(\mathbf{A}\times\mathbf{B}) \longrightarrow (-\mathbf{A})\times(-\mathbf{B}) = (\mathbf{A}\times\mathbf{B})$. That is, if $\mathbf{C} = \mathbf{A}\times\mathbf{B}$, $\boxed{\mathbf{C} \longrightarrow \mathbf{C}}$. *No* minus sign, in contrast to behavior of an "ordinary" vector, as given by (b). If $\mathbf{A}$ and $\mathbf{B}$ are *pseudovectors*, then $(\mathbf{A}\times\mathbf{B}) \longrightarrow (\mathbf{A})\times(\mathbf{B}) = (\mathbf{A}\times\mathbf{B})$. So the cross-product of two pseudovectors is again a *pseudovector*. In the cross-product of a vector and a pseudovector, one changes sign, the other doesn't, and therefore the cross-product is itself a *vector*. *Angular momentum* $(\mathbf{L} = \mathbf{r}\times\mathbf{p})$ and *torque* $(\mathbf{N} = \mathbf{r}\times\mathbf{F})$ are pseudovectors.

(d) $\mathbf{A}\cdot(\mathbf{B}\times\mathbf{C}) \longrightarrow (-\mathbf{A})\cdot((-\mathbf{B})\times(-\mathbf{C})) = -\mathbf{A}\cdot(\mathbf{B}\times\mathbf{C})$. So, if $a = \mathbf{A}\cdot(\mathbf{B}\times\mathbf{C})$, then $\boxed{a \longrightarrow -a;}$ a pseudoscalar *changes sign* under inversion of coordinates.

Problem 1.11

$$\boxed{\begin{aligned} &(a)\,\nabla f = 2x\,\hat{\mathbf{x}} + 3y^2\,\hat{\mathbf{y}} + 4z^3\,\hat{\mathbf{z}} \\ &(b)\,\nabla f = 2xy^3z^4\,\hat{\mathbf{x}} + 3x^2y^2z^4\,\hat{\mathbf{y}} + 4x^2y^3z^3\,\hat{\mathbf{z}} \\ &(c)\,\nabla f = e^x \sin y \ln z\,\hat{\mathbf{x}} + e^x \cos y \ln z\,\hat{\mathbf{y}} + e^x \sin y (1/z)\,\hat{\mathbf{z}} \end{aligned}}$$

Problem 1.12

(a) $\nabla h = 10[(2y - 6x - 18)\,\hat{\mathbf{x}} + (2x - 8y + 28)\,\hat{\mathbf{y}}]$. $\nabla h = 0$ at summit, so

$$\left.\begin{aligned} &2y - 6x - 18 = 0 \\ &2x - 8y + 28 = 0 \Longrightarrow 6x - 24y + 84 = 0 \end{aligned}\right\} 2y - 18 - 24y + 84 = 0.$$

$22y = 66 \Longrightarrow y = 3 \Longrightarrow 2x - 24 + 28 = 0 \Longrightarrow x = -2.$

Top is $\boxed{\text{3 miles north, 2 miles west, of South Hadley.}}$

(b) Putting in $x = -2$, $y = 3$:

$h = 10(-12 - 12 - 36 + 36 + 84 + 12) = \boxed{720 \text{ ft.}}$

(c) Putting in $x = 1$, $y = 1$: $\nabla h = 10[(2 - 6 - 18)\,\hat{\mathbf{x}} + (2 - 8 + 28)\,\hat{\mathbf{y}}] = 10(-22\,\hat{\mathbf{x}} + 22\,\hat{\mathbf{y}}) = 220(-\,\hat{\mathbf{x}} + \hat{\mathbf{y}})$.

$|\nabla h| = 220\sqrt{2} \approx \boxed{311 \text{ ft/mile}}$; direction: $\boxed{\text{northwest.}}$