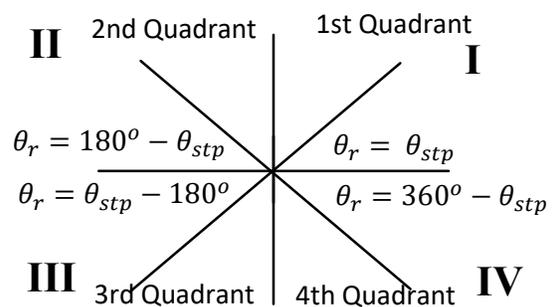
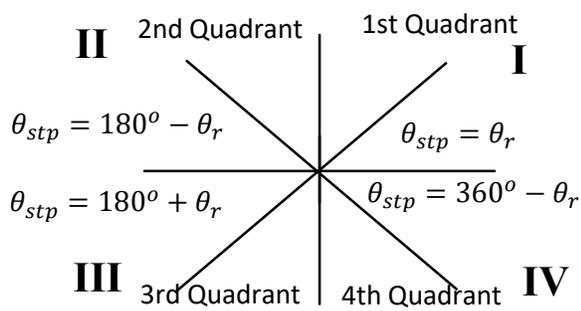
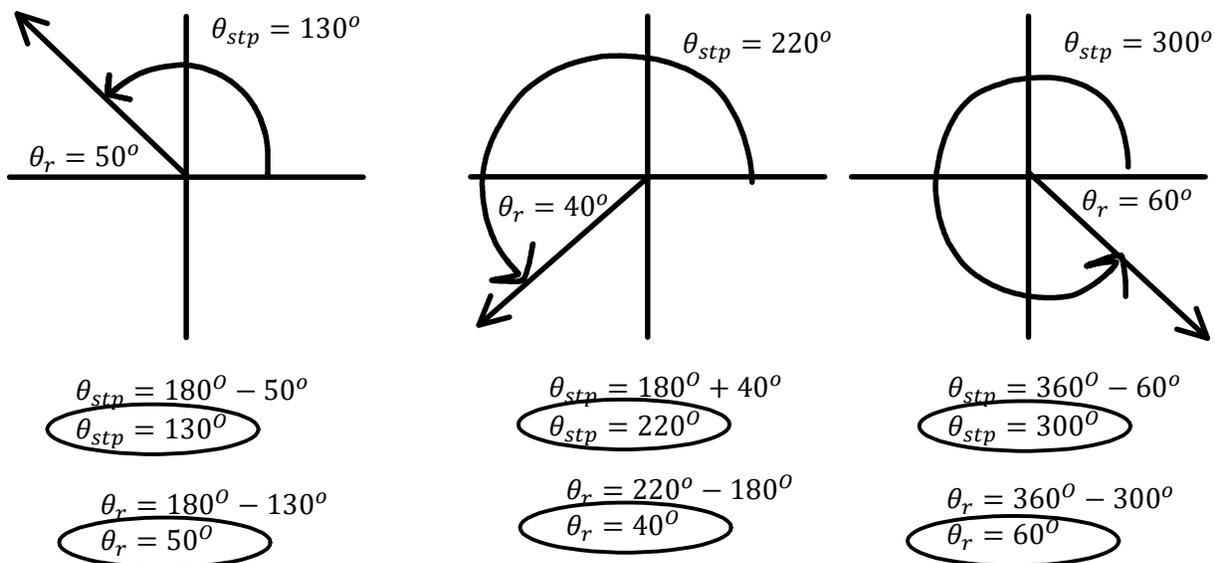
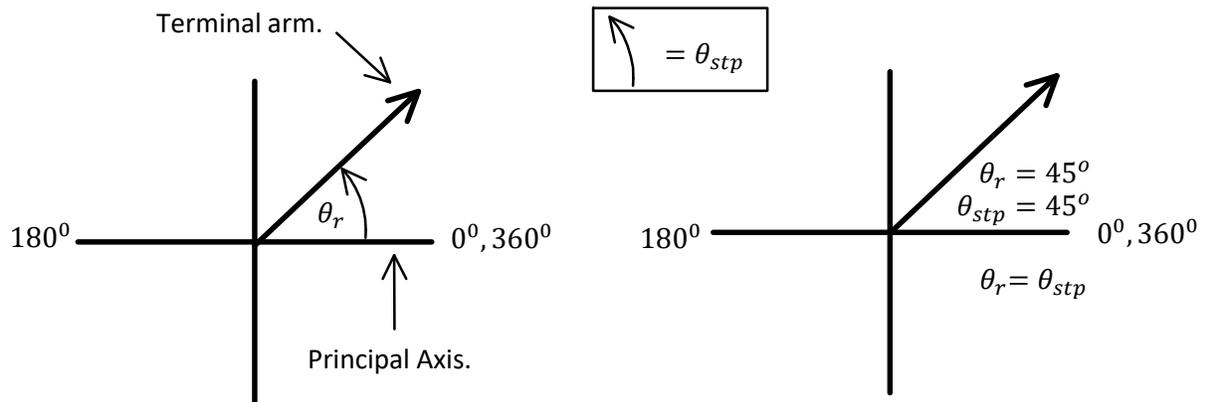


C11 - 2.1 - θ_r, θ_{stp} Notes

θ_r : the "reference angle" is the angle between the terminal arm and the x -axis ($0^\circ \leq \theta \leq 90^\circ$).

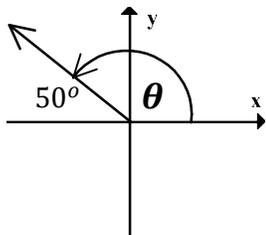
θ_{stp} : the "angle in standard position" from the principal axis (+ x -axis) to the terminal arm.



Basic logic will calculate θ_{stp} and θ_r much more easily than using these formulas.

C11 - 2.1 - $\pm \theta_{stp}, \theta_{cot}, \theta_{pri}$ Notes

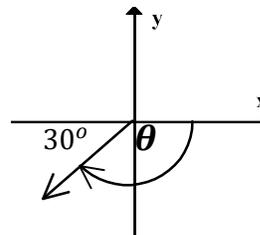
Counter-clockwise rotation is a positive θ_{stp}



$$\theta_{stp} = 180^\circ - 50^\circ$$

$$\theta_{stp} = 130^\circ$$

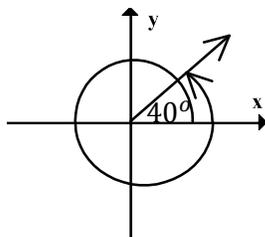
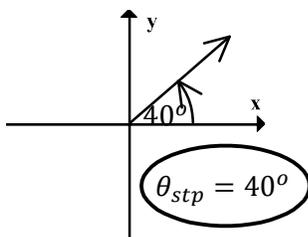
Clockwise rotation is a negative θ_{stp}



$$\theta_{stp} = -(180^\circ - 30^\circ)$$

$$\theta_{stp} = -150^\circ$$

Positive Co-terminal Angles (θ_{cot})



$$\theta_{cot} = \theta_{stp} \pm 360^\circ$$

$$\theta_{cot} = \theta_{stp} \pm 360^\circ$$

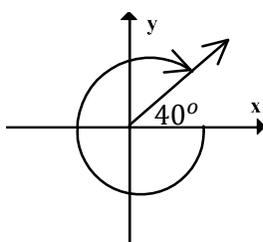
$$\theta_{cot} = 40^\circ + 360^\circ$$

$$\theta_{cot} = 400^\circ$$

$$\theta_{stp} = 40^\circ, \theta_{stp} = 400^\circ$$

$$\theta_{cot} = 40^\circ, 400^\circ, 760^\circ, 1120^\circ, 1480^\circ, \dots$$

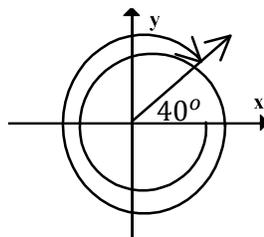
Negative Co-terminal Angles (θ_{cot})



$$\theta_{cot} = \theta_{stp} \pm 360$$

$$\theta_{cot} = 40 - 360$$

$$\theta_{cot} = -320^\circ$$



$$\theta_{cot} = \theta_{stp} \pm 360$$

$$\theta_{cot} = -320 - 360$$

$$\theta_{cot} = -680^\circ$$

$$\theta_{cot} = 40^\circ, -320^\circ, -680^\circ, -1040^\circ, -1400^\circ, \dots$$

$\theta_{principle} = \text{smallest} + \text{ve } \theta_{stp} \text{ coterminal.}$

$$\theta_{pri} = 0 \leq \theta_{cot} < 360$$

$$\theta_{stp} = 1000^\circ$$

$$\theta_{pri} = 1000^\circ - 360^\circ = 640^\circ$$

$$= 640^\circ - 360^\circ = 280^\circ$$

OR

$$1000^\circ - 2(360^\circ) = 280^\circ$$

$$\frac{1000^\circ}{360^\circ} = 2.777 \dots \quad \text{OR}$$

$$0.777 \dots \times 360^\circ = 280^\circ$$

You may need to add or subtract 360° more than once.