

Math 21C

Kouba

### Applications of Triple Integrals

Let  $R$  be a solid region in three-dimensional space and let  $\delta(P)$  be the density of the region at point  $P = (x, y, z)$ .

1.) VOLUME :  $\int_R 1 dV$  represents the *volume* of region  $R$ .

2.) AVERAGE VALUE :  $\frac{1}{\text{Volume of } R} \int_R f(x, y, z) dV$  represents the *average value* of function  $w = f(x, y, z)$  over region  $R$ .

3.) MASS :  $\int_R \delta(P) dV$  represents the *mass* of region  $R$ .

4.) MOMENT :

a.)  $\int_R (x - a)\delta(P) dV$  represents the *moment* of region  $R$  about the plane  $x = a$ .

b.)  $\int_R (y - b)\delta(P) dV$  represents the *moment* of region  $R$  about the plane  $y = b$ .

c.)  $\int_R (z - c)\delta(P) dV$  represents the *moment* of region  $R$  about the plane  $z = c$ .

5.) CENTER OF MASS,  $(\bar{x}, \bar{y}, \bar{z})$  :

a.)  $\bar{x} = \frac{\int_R x\delta(P) dV}{\int_R \delta(P) dV}$  represents the *x-coordinate* of the center of mass of region  $R$ .

b.)  $\bar{y} = \frac{\int_R y\delta(P) dV}{\int_R \delta(P) dV}$  represents the *y-coordinate* of the center of mass of region  $R$ .

c.)  $\bar{z} = \frac{\int_R z\delta(P) dV}{\int_R \delta(P) dV}$  represents the *z-coordinate* of the center of mass of region  $R$ .

6.) CENTROID,  $(\bar{x}, \bar{y}, \bar{z})$  :

a.)  $\bar{x} = \frac{\int_R x dV}{\int_R 1 dV}$  represents the *x-coordinate* of the centroid of region  $R$ .

b.)  $\bar{y} = \frac{\int_R y dV}{\int_R 1 dV}$  represents the *y-coordinate* of the centroid of region  $R$ .

c.)  $\bar{z} = \frac{\int_R z dV}{\int_R 1 dV}$  represents the *z-coordinate* of the center of mass of region  $R$ .

NOTE : The formulas for centroid follow immediately from the formulas for center of mass by letting density  $\delta(P) = 1$ .

7.) MOMENT OF INERTIA :  $\int_R (\text{distance})^2 \delta(P) dV$  represents the *moment of inertia* of region  $R$ , where *distance* refers to the distance from point  $P = (x, y, z)$  in region  $R$  to either a point or axis (line) of rotation.