# Vectors and plate motion

#### Geographic coordinates converted to vector form

Components for a radius vector **r** at latitude  $\lambda$  longitude  $\phi$  where *R* is radius of the Earth

 $\mathbf{r}_{x} = Rcos(\lambda)cos(\phi)$   $\mathbf{r}_{y} = Rcos(\lambda)sin(\phi)$   $\mathbf{r}_{z} = Rsin(\lambda)$ Components for a unit North arrow  $\hat{\mathbf{N}}$  at latitude  $\lambda$  longitude  $\phi$   $\mathbf{N}_{x} = -sin(\lambda)cos(\phi)$   $\mathbf{N}_{y} = -sin(\lambda)sin(\phi)$   $\mathbf{N}_{z} = cos(\lambda)$ Components for a unit East arrow  $\hat{\mathbf{E}}$  at longitude  $\phi$   $\mathbf{E}_{x} = -sin(\phi)$   $\mathbf{E}_{y} = cos(\phi)$  $\mathbf{E}_{z} = 0$ 

### Rate of plate motion at a point on boundary

For a point at angular distance  $\boldsymbol{\theta}$  from the Euler pole

 $v = \omega Rsin\theta$ 

where R is the radius of the Earth (6370 km),  $\omega$  is the rate of rotation in radians per million years, and v is the rate of slip in km per million years (or mm per year)

Alternatively, in vector terms, slip vector for motion  $_{A}\mathbf{v}_{B} = {}_{A}\mathbf{\Omega}_{B} \times \mathbf{r}_{i}$ 

where  $\mathbf{r}_{i}$  is the radius vector of the earth at the point on the plate boundary and  $_{A}\dot{\mathbf{U}}_{B}$  is the plate rotation vector

North component of  $_{\mathbf{A}}\mathbf{v}_{\mathbf{B}}$  is given by  $v_N = _{\mathbf{A}}\mathbf{v}_{\mathbf{B}} \cdot \hat{\mathbf{N}}$ East component of  $_{\mathbf{A}}\mathbf{v}_{\mathbf{B}}$  is given by  $v_E = _{\mathbf{A}}\mathbf{v}_{\mathbf{B}} \cdot \hat{\mathbf{E}}$ 

## Vector circuit for Euler poles

For any three plates A, B, C, if  ${}_{A}\Omega_{B}$  signifies rotation of plate B relative to plate A then  ${}_{A}\Omega_{B} + {}_{B}\Omega_{C} + {}_{C}\Omega_{A} = 0$ where  ${}_{A}\Omega_{B}$  signifies motion of A relative to B

### Vector circuit for triple junction

At a triple junction involving plates A, B, C, plate motion vectors obey  ${}_{A}\mathbf{v}_{B}+{}_{B}\mathbf{v}_{C}+{}_{C}\mathbf{v}_{A}=0$  where  ${}_{A}\mathbf{v}_{B}$  signifies motion of A relative to B

Note: sign conventions here follow the text by Van der Pluijm & Marshak (2004)