
basics - math

basics

Mar 31, 2025

CONTENTS

I	Linear Algebra	3
1	Matrices	5
1.1	Subspaces	5
1.2	Theorem	5
2	Matrix factorizations	7
2.1	Singular Value Decomposition	7
3	Linear Systems	11
II	Multivariable Calculus	13
4	Introduction to multi-variable calculus	15
4.1	Function	15
4.2	Limit	15
4.3	Derivatives	15
4.4	Integrals	15
4.5	Theorems	15
III	Differential Geometry	17
5	Introduction to Differential Geometry	19
5.1	Differential geometry in E^3	19
IV	Vector and Tensor Algebra and Calculus	21
6	Tensor Algebra	23
6.1	Basis	23
6.2	Exterior algebra	23
6.3	Exterior product	23
7	Tensor Calculus in Euclidean Spaces	25
7.1	Coordinates	25
7.2	Fields	26
7.3	Differential operators	26
7.4	Integrals in E^d , $d \leq 3$	30
7.5	Tensor Calculus in Euclidean Spaces - Cartesian coordinates in E^3	32
7.6	Tensor Calculus in Euclidean Spaces - cylindrical coordinates in E^3	34

7.7	Tensor Calculus in Euclidean Spaces - Spherical coordinates in E^3	37
8	Time derivative of integrals over moving domains	39
8.1	Volume density	39
8.2	Flux across a surface	39
8.3	Work line integral along a line	39
V	Functional Analysis	41
9	Introduction to Functional Analysis	43
10	Distributions (or generalized functions)	45
10.1	Dirac's delta	45
VI	Complex Calculus	49
11	Complex Analysis	51
11.1	Complex functions, $f : \mathbb{C} \rightarrow \mathbb{C}$	51
11.2	Holomorphic Functions - Analytic Functions	52
11.3	Useful integrals	53
11.4	Meromorphic functions	53
12	Laplace Transform	59
12.1	Inverse transform	59
12.2	Properties	59
13	Fourier Transforms	63
13.1	Fourier Series	63
13.2	Fourier Transform	64
13.3	Relations between Fourier transforms	66
VII	Calculus of Variations	69
14	Introduction to Calculus of Variations	71
14.1	Lagrange equations	72
VIII	Ordinary Differential Equations	77
15	Introduction to Ordinary Differential Equations	79
16	Linear Time-Invariant Systems	81
16.1	Impulsive force	82
16.2	Properties	82
IX	Partial Differential Equations	85
17	Introduction to Partial Differential Equations	87
17.1	Examples	87
17.2	Balance equations in physics	88

18 Elliptic equations	91
18.1 Poisson equation	91
19 Parabolic equations	93
19.1 Heat equation	93
20 Hyperbolic problems	95
20.1 Scalar linear	95
20.2 Scalar non-linear	95
20.3 System linear	95
20.4 System non-linear	99
20.5 n-dimensional space	99
21 Navier-Cauchy equations	105
21.1 Weak formulation	105
22 Navier-Stokes equations	107
22.1 Incompressibility constraint	107
22.2 Weak formulation of the problem	108
22.3 Non-linear term	108
23 Arbitrary Lagrangian-Eulerian description	109
23.1 Integral problem	109
23.2 Differential problem	110
Proof Index	111

This material is part of the [basics-books project](#). It is also available as a .pdf document.

Contents.

- **Linear Algebra.** ..., matrix factorization,...; basics of lots of numerical methods; **Vector and Tensor Algebra** provides the mathematical framework for manipulating vectors and tensors, the mathematical objects meant to represent **absolute quantities** - invariant under coordinate transformations - fundamental in geometry and physics.
- **Multivariable Calculus** provides the tools for working with continuous functions of many variables; **Differential Geometry** studies smooth curves, surfaces, volumes (and manifolds in general), within the framework of a Riemann structure, providing a metric to define distances, angles, curvatures and other geometric properties; **Vector and Tensor Calculus** studies vector and tensor fields defined on a manifold, along with their differentiation and integration, and thus being essential for a mature approach to geometry and physics;
- **Functional analysis** and **Complex Calculus** (complex analysis, transforms,...)
- ODEs
- PDEs
- Calculus of Variations: theoretical background; Lagrange multiplier method for constraints; sensitivity; gradient-based methods,...
- Optimization

Part I

Linear Algebra

MATRICES

$\mathbf{A} \in \mathbb{K}^{m,n}$ with usually $\mathbb{K}^{m,n} = \mathbb{R}^{m,n}$ or $\mathbb{C}^{m,n}$

Hermitian matrix. The Hermitian matrix \mathbf{A}^* of a matrix \mathbf{A} is the transpose and complex conjugate matrix (if $\mathbb{K} = \mathbb{C}$),

$$[\mathbf{A}^*]_{ij} = A_{ji}^*,$$

with the notation of a^* for the complex conjugate of a numerical quantity.

1.1 Subspaces

1.1.1 Range, Image

$$R(\mathbf{A}) = \{\mathbf{y} \in \mathbb{K}^m \mid \exists \mathbf{x} \in \mathbb{K}^n, \text{ s.t. } \mathbf{Ax} = \mathbf{y}\}$$

The range of a matrix \mathbf{A} is the linear space built on the columns of \mathbf{A} , since the operation \mathbf{Ax} represents nothing but a linear combination of the columns of matrix.

1.1.2 Null, Kernel

$$K(\mathbf{A}) = \{\mathbf{x} \in \mathbb{K}^n \mid \mathbf{Ax} = \mathbf{0}\}$$

1.2 Theorem

1.2.1 Orthogonality of $R(\mathbf{A})$ and $K(\mathbf{A}^*)$

The following holds,

$$R(\mathbf{A}) \perp K(\mathbf{A}^*),$$

meaning that $\forall \mathbf{u} \in R(\mathbf{A})$ and $\forall \mathbf{v} \in K(\mathbf{A}^*)$, $\mathbf{u}^* \mathbf{v} = 0$.

Proof.

$$\mathbf{u} = \mathbf{A}\mathbf{x}$$

$$\mathbf{0} = \mathbf{A}^*\mathbf{v}$$

and thus, premultiplication by \mathbf{x}^* of the second relation gives

$$0 = \mathbf{x}^*\mathbf{0} = \underbrace{\mathbf{x}^*\mathbf{A}^*}_{=(\mathbf{Ax})^*=\mathbf{u}^*} \mathbf{v} = \mathbf{u}^*\mathbf{v} .$$

This theorem becomes quite useful, e.g. for constrained linear systems and projections... (e.g. N-S, or other constrained linear systems...)

todo add links

MATRIX FACTORIZATIONS

- **Singular Value Decomposition (SVD)**
- **Spectral decomposition** Eigenvalues, eigenvectors; Jordan canonical formula...
- **QR**
- **LU**
- **Schur**
- **Cholesky** Symmetric positive definite matrices have Choleski decomposition,

$$\mathbf{M} = \mathbf{L}\mathbf{L}^*,$$

with \mathbf{L} lower triangular matrix. And thus quite easy to “invert”, for solving linear systems.

2.1 Singular Value Decomposition

Singular value decomposition of a matrix $\mathbf{A} \in \mathbb{C}^{m,n}$

$$\mathbf{A}_{(m,n)} = (\text{SVD}) = \mathbf{U}_{(m,m)} \mathbf{S}_{(m,n)} \mathbf{V}_{(n,n)}^*$$

with $\mathbf{U}^* \mathbf{U} = \mathbf{I}_{(m,m)}$, and $\mathbf{V}^* \mathbf{V} = \mathbf{I}_{(n,n)}$, $\mathbf{S} = \text{diag}\{\sigma_i\}$, $\sigma_i \geq 0$.

Exploiting the definition of matrix product, the SVD of matrix \mathbf{A} can be written as

$$\mathbf{A} = \sum_{i=\min(m,n)} \sigma_i \mathbf{u}_i \mathbf{v}_i^*,$$

see also economic decomposition below.

2.1.1 Properties

Relation with *range* and *kernel* the matrix.

$$\mathbf{R}(\mathbf{A}) = \{\mathbf{u}_i | \sigma_i > 0\}$$

$$\mathbf{K}(\mathbf{A}) = \{\mathbf{v}_i | \sigma_i = 0\}$$

$$\mathbf{R}(\mathbf{A}^*) = \{\mathbf{v}_i | \sigma_i > 0\}$$

$$\mathbf{K}(\mathbf{A}^*) = \{\mathbf{u}_i | \sigma_i = 0\}$$

It's immediate to prove $\mathbf{R}(\mathbf{A}) \perp \mathbf{K}(\mathbf{A}^*)$.

Full or economic decomposition. In general the \mathbf{S} of the full decomposition is not square.

$$\mathbf{A} = (\text{SVD}) = \mathbf{U}_{(m,m)} \mathbf{S}_{(m,n)} \mathbf{V}_{(n,n)}^* = \mathbf{U}_{(m,k)}^e \mathbf{S}_{(k,k)}^e \mathbf{V}_{(k,n)}^{e*},$$

with $k = \min(m, n)$.

2.1.2 Applications

Solution of under-determined linear systems

Norms and optimization

If L^2 -norm is used for vector norms, see [Example 2.1.1](#)

$$\text{Find } \max_{\|\mathbf{x}\|=1} \|\mathbf{A}\mathbf{x}\|^2$$

$$\mathbf{x}^* \mathbf{A}^* \mathbf{A} \mathbf{x} = \mathbf{x}^* \mathbf{V} \mathbf{S}^* \underbrace{\mathbf{U}^* \mathbf{U}}_{\mathbf{I}} \mathbf{S} \underbrace{\mathbf{V} \mathbf{V}^*}_{\mathbf{z}}$$

and $\mathbf{z} = \mathbf{V}^* \mathbf{x}$ is unitary as well (since $1 = \mathbf{x}^* \mathbf{x} = \mathbf{z}^* \mathbf{V}^* \mathbf{V} \mathbf{z} = \mathbf{z}^* \mathbf{z}$).

After defining $\mathbf{S}_2 := \mathbf{S}^* \mathbf{S}$, the problem thus becomes

$$\text{Find } \max_{\|\mathbf{z}\|=1} \mathbf{z}^* \mathbf{S}_2 \mathbf{z}$$

Manipulating the objective function as $\sum_i \sigma_i^2 |z_i|^2$, the constraint optimization problem has global maximum σ_1^2 (sorted singular values from the largest to the smallest) when $\mathbf{z}_1 = (1, 0, 0, \dots, 0)^T$. Going back to the original variable, optimal condition

- is achieved for $\mathbf{x}_1 = \mathbf{v}_1$;
- has value $\max_{\|\mathbf{x}\|=1} \|\mathbf{A}\mathbf{x}\| = \sigma_1$
- and the response of the system is $\mathbf{y}_1 = \sigma_1 \mathbf{u}_1$ as

$$\mathbf{y}_1 := \mathbf{A} \mathbf{x}_1 = \mathbf{U} \mathbf{S} \mathbf{V}^* \mathbf{v}_1 = \sum_k (\sigma_k \mathbf{u}_k \mathbf{v}_k^*) \mathbf{v}_1 = \sigma_1 \mathbf{u}_1.$$

Example 2.1.1 (Other norms - variations of the L^2 -norm)

This kind of problem may result as the discrete counterpart of a continuous problem, as an example from finite element methods, where \mathbf{x}, \mathbf{y} contain the coefficients of the basis functions. In this case, the discrete counterpart of the continuous norm-measure of the continuous fields may involve a “mass matrix” (symmetric, definite positive - and thus with Choleski factorization...),

$$\begin{aligned} \int_{\Omega_x} |x(\vec{r})|^2 d\vec{r} &\simeq \mathbf{x}^* \mathbf{M}_x \mathbf{x} \\ \int_{\Omega_y} |y(\vec{r})|^2 d\vec{r} &\simeq \mathbf{y}^* \mathbf{M}_y \mathbf{y} \end{aligned}$$

Continuous and discrete optimization problems are

$$\text{Find } \max_{|x(\vec{r})|_{L^2(\Omega_x)}=1} |y|_{L^2(\Omega_y)}^2$$

$$\text{Find } \max_{\mathbf{x}^* \mathbf{M}_x \mathbf{x}=1} \mathbf{x}^* \mathbf{A}^* \mathbf{M}_y \mathbf{A} \mathbf{x}$$

with the relation $\mathbf{y} = \mathbf{A}\mathbf{x}$ between the discrete input and output.

This problem can be easily (and efficiently?) recast to the standard form of the problem, using *Cholesky decomposition* of matrix $\mathbf{M}_x = \mathbf{L}_x \mathbf{L}_x^*$, with the definition of the variable $\mathbf{z} = \mathbf{L}_x^* \mathbf{x}$

$$\text{Find } \max_{\|\mathbf{z}\|=1} \mathbf{z}^* \mathbf{L}_x^{-1} \mathbf{A}^* \mathbf{L}_y \mathbf{L}_y^* \mathbf{A} \mathbf{L}_x^{-*} \mathbf{z}$$

This problem can be efficiently solved with iterative algorithms to compute the SVD of the matrix $\tilde{\mathbf{A}} := \mathbf{L}_y^* \mathbf{A} \mathbf{L}_x^{-*}$, that doesn't need the expensive full inversion of a matrix but only its action on a vector (instead of evaluating the inverse, a linear system - here triangular! Easier to solve - can be efficiently solved). Algorithms like **Arnoldi algorithm** evaluates the largest eigenvalues or singular values (if no options to set other goals) and the corresponding eigenvectors and singular vectors, alternating **power iterations** and **orthogonalization**. Here power iteration to evaluate the action of the matrix $\tilde{\mathbf{A}} = \mathbf{L}_y^* \mathbf{A} \mathbf{L}_x^{-*}$ on a generic vector \mathbf{z} is made of the following steps:

1. solution of the linear system $\mathbf{L}_x^* \mathbf{a} = \mathbf{z} \rightarrow \mathbf{a} = \dots$
2. matrix-vector multiplication $\mathbf{b} = \mathbf{A} \mathbf{a}$
3. matrix-vector multiplication $\mathbf{c} = \mathbf{L}_y^* \mathbf{b}$

Once the SVD is solved, with $\mathbf{z}_1 = \mathbf{v}_1$

$$\begin{aligned} \mathbf{x}_1 &= \mathbf{L}_x^{-*} \mathbf{v}_1 \\ \mathbf{y}_1 &= \mathbf{A} \mathbf{x}_1 = \sigma_1 \mathbf{L}_y^{-*} \mathbf{u}_1 \end{aligned}$$

LINEAR SYSTEMS

The linear system

$$\mathbf{Ax} = \mathbf{b}$$

with $\mathbf{A} \in \mathbb{R}^{m,n}$, $\mathbf{x} \in \mathbb{R}^n$, $\mathbf{b} \in \mathbb{R}^m$ has solution if there exists (at least) a vector $\tilde{\mathbf{x}}$ whose product with \mathbf{A} gives \mathbf{b} .

Condition for the existence of a solution. A solution exists if \mathbf{b} belongs to the *range of \mathbf{A}* .

Uniqueness of a solution. If a solution $\tilde{\mathbf{x}}$ exists, it's unique if the *kernel of \mathbf{A}* is empty, $K(\mathbf{A}) = \emptyset$. If the kernel is not empty,

$$\mathbf{b} = \mathbf{A}(\tilde{\mathbf{x}} + \mathbf{u}) = \mathbf{A}\tilde{\mathbf{x}} + \underbrace{\mathbf{A}\mathbf{u}}_{=\mathbf{0}},$$

for $\forall \mathbf{u} \in K(\mathbf{A})$, and thus an infinite number of solutions exists. Given a vector basis of the kernel $\mathbf{K}(\mathbf{A})$, where $\dim(K(\mathbf{A})) = n_K$, $\{\mathbf{u}_1, \dots, \mathbf{u}_{n_K}\}$, the general solution has n_K “degrees of arbitrariness”, since the general solution of the problem is

$$\tilde{\mathbf{x}} + \sum_{i=1}^{n_K} a_i \mathbf{u}_i = \tilde{\mathbf{x}} + \mathbf{U}\mathbf{a}.$$

todo treat under-, det-, over-determined lin sys

Part II

Multivariable Calculus

INTRODUCTION TO MULTI-VARIABLE CALCULUS

4.1 Function

4.2 Limit

4.3 Derivatives

4.4 Integrals

4.5 Theorems

4.5.1 Green's lemma

$$\begin{aligned}\int_S \frac{\partial F}{\partial y} dx dy &= - \oint_{\partial S} F dx \\ \int_S \frac{\partial G}{\partial x} dx dy &= \oint_{\partial S} G dy\end{aligned}$$

Proof for simple domains.

In a simple domain in x , so that the closed contour ∂S is delimited by the curves $y = Y_1(x)$, $y = Y_2(x) > Y_1(x)$, for $x \in [x_1, x_2]$,

$$\begin{aligned}\int_S \frac{\partial F}{\partial y} dx dy &= \int_{x=x_1}^{x_2} \int_{y=Y_1(x)}^{Y_2(x)} \frac{\partial F}{\partial y} dy dx = \\ &= \int_{x=x_1}^{x_2} [F(x, Y_2(x)) - F(x, Y_1(x))] dx = \\ &= - \int_{x=x_1}^{x_2} F(x, Y_1(x)) dx - \int_{x=x_2}^{x_1} F(x, Y_2(x)) dx = \\ &= - \oint_{\partial S} F(x, y) dx\end{aligned}$$

In a simple domain in y , so that the closed contour ∂S is delimited by the curves $x = X_1(y)$, $x = X_2(y) > X_1(y)$ for $y \in [y_1, y_2]$,

$$\begin{aligned}
 \int_S \frac{\partial G}{\partial x} dx dy &= \int_{y=y_1}^{y_2} \int_{x=X_1(y)}^{X_2(y)} \frac{\partial G}{\partial x} dx dy = \\
 &= \int_{y=y_1}^{y_2} [G(X_2(y), y) - G(X_1(y), y)] dy = \\
 &= \int_{y=y_1}^{y_2} G(X_1(y), y) dy + \int_{y=y_2}^{y_1} G(X_2(y), y) dy = \\
 &= \oint_{\partial S} G(x, y) dy
 \end{aligned}$$

Part III

Differential Geometry

INTRODUCTION TO DIFFERENTIAL GEOMETRY

5.1 Differential geometry in E^3

5.1.1 Curves

Parametric representation of curve in 3-dimensional (Euclidean) space E^3

$$\vec{r}(q)$$

Differential, $d\vec{r}$.

$$d\vec{r}(q) = \vec{r}'(q) dq .$$

Arc-length parameter, s . So that $ds = |d\vec{r}(s)|$ and thus

$$|d\vec{r}(s)| = |\vec{r}'(s)| |ds| \quad \rightarrow \quad |\vec{r}'(s)| = 1 \quad \rightarrow \quad \vec{r}'(s) = \hat{t}(s) .$$

Frenet basis. Using arc-length parameter, Frenet basis is naturally defined as the set $\{\hat{t}, \hat{n}, \hat{b}\}$:

- tangent unit vector, $\hat{t}(s) = \vec{r}'(s)$,
- normal unit vector, $\hat{r}''(s) = \hat{t}'(s) =: \kappa(s) \hat{n}(s)$, with $\kappa(s)$ local curvature
- binormal unit vector, $\hat{b}(s) = \hat{t}(s) \times \hat{n}(s)$

Using a general parameter, t , with some abuse of notation $\vec{r}(t) = \vec{r}(s(t))$ and indicating $\dot{(\)} = \frac{d}{dt}$,

- $\dot{\vec{r}} = \frac{ds}{dt} \frac{d\vec{r}}{ds} = \dot{s} \hat{t}$
- $\ddot{\vec{r}} = \frac{d}{dt} \dot{\vec{r}} = \frac{d}{dt} (\dot{s} \hat{t}) = \ddot{s} \hat{t} + \frac{ds}{dt} \frac{d}{ds} \hat{t} = \ddot{s} \hat{t} + \dot{s}^2 \kappa \hat{n}$

Osculator circle. Circle with $R(s) = \frac{1}{\kappa(s)}$, in plane orthogonal to $\hat{b}(s)$, passing through $\vec{r}(s)$, and thus center in $\vec{r}_C(s) = \vec{r}(s) + \hat{n}R(s)$. Its parametric representation using its arc-length parameter p , with $\vec{r}(p=0) = \vec{r}(s)$ reads

$$\vec{r}(p) = \vec{r}_C(s) + R(s) \left[-\cos\left(\frac{p}{R(s)}\right) \hat{n}(s) + \sin\left(\frac{p}{R(s)}\right) \hat{t}(s) \right] .$$

Its first and second order derivatives w.r.t. the arc-length p evaluated in $p=0$, i.e. $\vec{r} = \vec{r}(s)$ read:

- first derivative in $p=0$,

$$\hat{t}(p)|_{p=0} = \vec{r}'(p)|_{p=0} = \left[\sin\left(\frac{p}{R(s)}\right) \hat{n}(s) + \cos\left(\frac{p}{R(s)}\right) \hat{t}(s) \right] \Big|_{p=0} = \hat{t}(s) ,$$

i.e. the osculator circle has the same tangent as the curve in the point.

- second derivative in $p = 0$,

$$\kappa(p)\hat{n}(p)|_{p=0} = \vec{r}''(p)|_{p=0} = \frac{1}{R(s)} \left[\cos\left(\frac{p}{R(s)}\right) \hat{n}(s) - \sin\left(\frac{p}{R(s)}\right) \hat{t}(s) \right] \Big|_{p=0} = \frac{1}{R(s)} \hat{n}(s) = \kappa(s)\hat{n}(s),$$

i.e. the osculator circle has the same normal vector and curvature as the curve in the point.

5.1.2 Surfaces

$$\begin{aligned} \vec{r}(q^1, q^2) \\ d\vec{r} = \frac{\partial \vec{r}}{\partial q^1} dq^1 + \frac{\partial \vec{r}}{\partial q^2} dq^2 = \vec{b}_1 dq^1 + \vec{b}_2 dq^2 \end{aligned}$$

A third vector $\vec{b}_3 := \hat{n}$ can be defined so that $|\hat{n}| = 1$ and $\hat{n} \cdot \vec{b}_i = 0, i = 1 : 2$. For $i = 1 : 2, k = 1 : 2$

$$\frac{\partial \vec{b}_i}{\partial q^j} = \Gamma_{ij}^k \vec{b}_k = \Gamma_{ij}^1 \vec{b}_1 + \Gamma_{ij}^2 \vec{b}_2 + \Gamma_{ij}^3 \vec{b}_3$$

so that

$$\Gamma_{ij}^k = \vec{b}^k \cdot \frac{\partial \vec{b}_i}{\partial q^j}$$

Normal vector.

$$\vec{n}(q^1, q^2) = \frac{\partial \vec{r}}{\partial q^1}(q^1, q^2) \times \frac{\partial \vec{r}}{\partial q^2}(q^1, q^2) = \vec{b}_1(q^1, q^2) \times \vec{b}_2(q^1, q^2)$$

Tangent plane.

$$(\vec{r} - \vec{r}(q^1, q^2)) \cdot \vec{n}(q^1, q^2) = 0$$

Length of elementary segment.

$$\begin{aligned} |d\vec{r}|^2 &= d\vec{r} \cdot d\vec{r} = \\ &= (\vec{b}_1 dq^1 + \vec{b}_2 dq^2) \cdot (\vec{b}_1 dq^1 + \vec{b}_2 dq^2) = \\ &= g_{11} dq^1 dq^1 + g_{12} dq^1 dq^2 + g_{21} dq^2 dq^1 + g_{22} dq^2 dq^2 = g_{ij} dq^i dq^j \end{aligned}$$

Second order approximation.

$$\begin{aligned} \vec{r}(q^1 + dq^1, q^2 + dq^2) &= \vec{r}(q_1, q_2) + \frac{\partial \vec{r}}{\partial q^i} dq^i + \frac{\partial^2 \vec{r}}{\partial q^i \partial q^j} dq^i dq^j = \\ &= \vec{r}(q_1, q_2) + \vec{b}_i dq^i + \vec{b}_k \Gamma_{ij}^k dq^i dq^j + \hat{n} \Gamma_{ij}^3 dq^i dq^j \end{aligned}$$

so that

$$\begin{aligned} [\vec{r}(q^1 + dq^1, q^2 + dq^2) - \vec{r}(q^1, q^2)] \cdot \hat{n} &= \Gamma_{ij}^3 dq^i dq^j = \\ &= \hat{n} \cdot \frac{\partial^2 \vec{r}}{\partial q^i \partial q^j} dq^i dq^j = \\ &= \hat{n} \cdot \frac{\partial^2 \vec{r}}{\partial q^i \partial q^j} \vec{b}^i \cdot \vec{b}_k dq^k \vec{b}^j \cdot \vec{b}_l dq^l = \\ &= \underbrace{dq^k \vec{b}_k}_{d\vec{r}} \cdot \left[\hat{n} \cdot \frac{\partial^2 \vec{r}}{\partial q^i \partial q^j} \vec{b}^i \otimes \vec{b}^j \right] \cdot \underbrace{dq^l \vec{b}_l}_{d\vec{r}} \end{aligned}$$

Curvature tensor.

Part IV

Vector and Tensor Algebra and Calculus

TENSOR ALGEBRA**6.1 Basis**

Definition 6.1.1 (Basis)

Definition 6.1.2 (Reciprocal basis)

In a inner product space, the reciprocal basis of a given basis $\{\vec{b}_a\}_{a=1:d}$ is the set of vectors $\{\vec{b}_b\}_{b=1:d}$, s.t.

$$\vec{b}^b \cdot \vec{b}_a = \delta_a^b .$$

6.2 Exterior algebra \wedge **6.3 Exterior product**

Generalization of the vector product

TENSOR CALCULUS IN EUCLIDEAN SPACES

This section deals with tensor calculus in Euclidean space or on manifolds embedded in Euclidean spaces, focusing on d -dimensional spaces with $d \leq 3$, with *inner product*.

This section may rely on results of *differential geometry*.

7.1 Coordinates

A set of parameters $\{q^a\}_{a=1:d}$ to represent vector (or point) in space,

$$\vec{r}(q^a)$$

if $\vec{r} \in E^d$, $a = 1 : d$.

In E^3 ,

- **Coordinate lines**, 2-parameter family of lines, keeping 2 coordinates constant. As an example, coordinate lines with constant q^2, q^3

$$\vec{r}_1(q^1) = \vec{r}(q^1, \bar{q}^2, \bar{q}^3) .$$

- **Coordinate surfaces**, 1-parameter family of surfaces, keeping 1 coordinate constant. As an example, coordinate surfaces with constant q^1 ,

$$\vec{r}_{23}(q^2, q^3) = \vec{r}(\bar{q}^1, q^2, q^3) .$$

Definition 7.1.1 (Regular parametrization)

If $\frac{\partial \vec{r}}{\partial q^a} \neq 0$.

7.1.1 Natural basis

Definition 7.1.2 (Natural basis)

Vectors of natural basis

$$\vec{b}_a := \frac{\partial \vec{r}}{\partial q^a}$$

Definition 7.1.3 (Reciprocal basis (todo move to Tensor Algebra))

Given a basis $\{\vec{b}_a\}_a$, its reciprocal basis the set of vector $\{\vec{b}^b\}_b$ defined as

$$\vec{b}^b \cdot \vec{b}_a = \delta_a^b,$$

being δ_a^b Kronecker delta.

Definition 7.1.4 (Christoffel symbols)

Christoffel symbols (of the 2^{nd} kind) are defined as the components of the partial derivatives of the vectors of a natural basis w.r.t. the coordinates referred to the natural basis itself,

$$\frac{\partial \vec{b}_a}{\partial q^b} = \Gamma_{ab}^c \vec{b}_c \quad (7.1)$$

Properties of Christoffel symbols

Exploiting the definition of reciprocal basis, Christoffel symbols can be written as

$$\Gamma_{ab}^c = \vec{b}^c \cdot \frac{\partial \vec{b}_a}{\partial q^b}.$$

Symmetry. Symmetry on the lower indices

$$\Gamma_{ab}^c = \Gamma_{ba}^c,$$

readily follows Schwartz theorem about partial derivatives

$$\frac{\partial \vec{b}_a}{\partial q^b} = \frac{\partial}{\partial q^c} \frac{\partial \vec{r}}{\partial q^a} = \frac{\partial}{\partial q^a} \frac{\partial \vec{r}}{\partial q^b} = \frac{\partial \vec{b}_b}{\partial q^a}$$

7.2 Fields

Function of the points in space $F : E^d \rightarrow V^r$, being V^r a space of tensors of order r .

7.3 Differential operators

7.3.1 Directional derivative

$$F(\vec{r}) = F(\vec{r}(q^a)) = f(q^a)$$

$$f(q^a + \beta \Delta q^a) = F(\vec{r}(q^a + \beta \Delta q^a))$$

$$\vec{r}(q^a) + \alpha \vec{v} = \vec{r}(q^a + \beta \Delta q^a) \sim \vec{r}(q^a) + \frac{\partial \vec{r}}{\partial q^b} \beta \Delta q^b$$

$$\alpha \vec{v} \sim \beta \frac{\partial \vec{r}}{\partial q^b}(q^a) \Delta q^b = \beta \vec{b}_b(q^a) \Delta q^b \quad \rightarrow \quad \Delta q^b = \frac{\alpha}{\beta} \vec{b}^b(q^a) \cdot \vec{v}$$

The directional derivative for an arbitrary vector $\vec{v} \in V$

$$\left. \frac{d}{d\alpha} F(\vec{r} + \alpha \vec{v}) \right|_{\alpha=0}$$

is evaluated as the limit for $\alpha \rightarrow 0$ of the incremental ratio

$$\begin{aligned} \frac{F(\vec{r} + \alpha \vec{v}) - F(\vec{r})}{\alpha} &\sim \frac{f(q^a + \beta \Delta q^a) - f(q^a)}{\alpha} = \\ &\sim \frac{1}{\alpha} \frac{\partial f}{\partial q^b}(q^a) \beta \Delta q^b = \\ &\sim \vec{v} \cdot \vec{b}^b(q^a) \frac{\partial f}{\partial q^b}(q^a) = \\ &= \vec{v} \cdot \nabla F(\vec{r}) \end{aligned}$$

7.3.2 Gradient

The gradient is the differential operator is the first-order differential operator appearing in the definition of the directional derivative, $\nabla F(\vec{r})$. It takes a tensor field $F(\vec{r})$ of order r and gives a tensor field $\nabla F(\vec{r})$ of order $r + 1$. Given a set of coordinates $\{q^a\}_{a=1:d}$, the gradient can be written using the reciprocal basis of the natural basis as

$$\nabla F(\vec{r}) = \vec{b}^b(\vec{r}) \frac{\partial F}{\partial q^b}(\vec{r}) \quad (7.2)$$

Examples. ...

Example 7.3.1 (Gradient of a scalar field - with general coordinates q^a)

Applying the definition (7.2) of gradient operator, it readily follows

$$\nabla F = \vec{b}^a \frac{\partial F}{\partial q^a}$$

Example 7.3.2 (Gradient of a vector field - with general coordinates q^a)

Applying the definition (7.2) of gradient operator, rule for the derivative of a product and the definition (7.1) of Christoffel symbols to write derivatives of base vectors,

$$\begin{aligned} \nabla F &= \vec{b}^a \frac{\partial}{\partial q^a} (F^b \vec{b}_b) = \\ &= \vec{b}^a \left[\frac{\partial F^b}{\partial q^a} \vec{b}_b + F^b \frac{\partial \vec{b}_b}{\partial q^a} \right] = \\ &= \vec{b}^a \left[\frac{\partial F^b}{\partial q^a} \vec{b}_b + F^b \Gamma_{ab}^c \vec{b}_c \right] = \\ &= \vec{b}^a \otimes \vec{b}_b \left[\frac{\partial F^b}{\partial q^a} + \Gamma_{ac}^b F^c \right]. \end{aligned}$$

Example 7.3.3 (Gradient of a 2^{nd} -order tensor field - with general coordinates q^a)

Applying the definition (7.2) of gradient operator, rule for the derivative of a product and the definition (7.1) of Christoffel symbols to write derivatives of base vectors,

$$\begin{aligned}
 \nabla F &= \vec{b}^a \frac{\partial}{\partial q^a} (F^{bc} \vec{b}_b \otimes \vec{b}_c) = \\
 &= \vec{b}^a \left[\frac{\partial F^{bc}}{\partial q^a} \vec{b}_b \vec{b}_c + F^{bc} \frac{\partial \vec{b}_b}{\partial q^a} \vec{b}_c + F^{bc} \vec{b}_b \frac{\partial \vec{b}_c}{\partial q^a} \right] = \\
 &= \vec{b}^a \left[\frac{\partial F^{bc}}{\partial q^a} \vec{b}_b \vec{b}_c + F^{bc} \Gamma_{ab}^d \vec{b}_d \vec{b}_c + F^{bc} \Gamma_d^{ac} \vec{b}_b \vec{b}_d \right] = \\
 &= \vec{b}^a \otimes \vec{b}_b \otimes \vec{b}_c \left[\frac{\partial F^{bc}}{\partial q^a} + \Gamma_{ad}^b F^{dc} + \Gamma_{ad}^c F^{bd} \right].
 \end{aligned}$$

7.3.3 Divergence

Divergence operator is a first-order differential operator that can be defined as the contraction of the first two indices of the gradient,

$$\nabla \cdot F = C_1^2 (\nabla F) .$$

It takes a tensor field $F(\vec{r})$ of order $r \geq 1$ and gives a tensor field $\nabla \cdot F(\vec{r})$ of order $r - 1 \geq 0$.

Example 7.3.4 (Divergence of a vector field - with general coordiantes q^a)

Applying contraction to the gradient of a vector field, it readily follows,

$$\begin{aligned}
 \nabla \cdot (F^b \vec{b}_b) &= C_1^2 (\nabla F) = \\
 &= C_1^2 \left(\vec{b}^a \otimes \vec{b}_b \left[\frac{\partial F^b}{\partial q^a} + \Gamma_{ac}^b F^c \right] \right) = \\
 &= \frac{\partial F^a}{\partial q^a} + \Gamma_{ac}^a F^c
 \end{aligned}$$

Example 7.3.5 (Divergence of a 2^{nd} -order tensor field - with general coordiantes q^a)

Applying contraction to the gradient of a vector field, it readily follows,

$$\begin{aligned}
 \nabla \cdot (F^{bc} \vec{b}_b \otimes \vec{b}_c) &= C_1^2 (\nabla F) = \\
 &= C_1^2 \left(\vec{b}^a \otimes \vec{b}_b \otimes \vec{b}_c \left[\frac{\partial F^{bc}}{\partial q^a} + \Gamma_{ad}^b F^{dc} + \Gamma_{ad}^c F^{bd} \right] \right) = \\
 &= \vec{b}_c \left[\frac{\partial F^{ac}}{\partial q^a} + \Gamma_{ad}^a F^{dc} + \Gamma_{ad}^c F^{ad} \right]
 \end{aligned}$$

7.3.4 Laplacian

Laplacian operator is second-order differential operator that can be defined as the divergence of the gradient,

$$\Delta F = \nabla^2 F = \nabla \cdot \nabla F .$$

Example 7.3.6 (Laplacian of a scalar field - with general coordinates q^a)

$$\begin{aligned} \nabla \cdot \nabla F &= C_1^2 [\nabla (\nabla F)] = \\ &= C_1^2 \left[\nabla \left(\vec{b}^a \frac{\partial F}{\partial q^a} \right) \right] = \\ &= C_1^2 \left[\nabla \left(\vec{b}_b g^{ab} \frac{\partial F}{\partial q^a} \right) \right] = \\ &= C_1^2 \left[\vec{b}^c \frac{\partial}{\partial q^c} \left(\vec{b}_b g^{ab} \frac{\partial F}{\partial q^a} \right) \right] = \\ &= C_1^2 \left\{ \vec{b}^c \left[\vec{b}_b \frac{\partial}{\partial q^c} \left(g^{ab} \frac{\partial F}{\partial q^a} \right) + g^{ab} \frac{\partial F}{\partial q^a} \frac{\partial \vec{b}_b}{\partial q^c} \right] \right\} = \\ &= C_1^2 \left\{ \vec{b}^c \left[\vec{b}_b \frac{\partial}{\partial q^c} \left(g^{ab} \frac{\partial F}{\partial q^a} \right) + g^{ab} \frac{\partial F}{\partial q^a} \Gamma_{bc}^d \vec{b}_d \right] \right\} = \\ &= C_1^2 \left\{ \vec{b}^c \vec{b}_b \left[\frac{\partial}{\partial q^c} \left(g^{ab} \frac{\partial F}{\partial q^a} \right) + g^{ad} \Gamma_{cd}^b \frac{\partial F}{\partial q^a} \right] \right\} = \\ &= \frac{\partial}{\partial q^b} \left(g^{ab} \frac{\partial F}{\partial q^a} \right) + g^{ad} \Gamma_{bd}^a \frac{\partial F}{\partial q^a} . \end{aligned}$$

Example 7.3.7 (Laplacian of a vector field - with general coordinates q^a)

$$\begin{aligned} \nabla \cdot \nabla F &= C_1^2 [\nabla (\nabla F)] = \\ &= C_1^2 \left\{ \nabla \left[\vec{b}^a \vec{b}_b \left(\frac{\partial F^b}{\partial q^a} + \Gamma_{ac}^b F^c \right) \right] \right\} = \\ &= C_1^2 \left\{ \nabla \left[\vec{b}_c \vec{b}_b g^{ac} \left(\frac{\partial F^b}{\partial q^a} + \Gamma_{ac}^b F^c \right) \right] \right\} = \\ &= C_1^2 \left\{ \nabla \cdot \left((\nabla F)^{cb} \vec{b}_c \vec{b}_b \right) \right\} = \\ &= C_1^2 \left\{ \vec{b}^a \vec{b}_c \vec{b}_b \left[\frac{\partial (\nabla F)^{cb}}{\partial q^a} + \Gamma_{ad}^c (\nabla F)^{db} + \Gamma_{ad}^b (\nabla F)^{cd} \right] \right\} = \\ &= \vec{b}_b \left[\frac{\partial (\nabla F)^{ab}}{\partial q^a} + \Gamma_{ad}^a (\nabla F)^{db} + \Gamma_{ad}^b (\nabla F)^{ad} \right] = . \end{aligned}$$

7.3.5 Curl

7.4 Integrals in E^d , $d \leq 3$

7.4.1 Line integrals

Density

Integrals

$$\int_{\vec{r} \in \gamma} F(\vec{r})$$

represent the summation of contributions $F(\vec{r})$ over elementary segments of path γ , whose dimension is $|d\vec{r}|$, i.e. implicitly means

$$\int_{\vec{r} \in \gamma} F(\vec{r}) = \int_{\vec{r} \in \gamma} F(\vec{r}) |d\vec{r}| .$$

Given a regular parametrization of the curve $\vec{r}(q^1)$ (with increasing q^1 so that $|dq^1| = dq^1$), and the differential $d\vec{r} = \vec{r}'(q^1) dq^1$, the integral can be written as an integral in the parameter q^1

$$\int_{q=q_a^1}^{q_b^1} F(\vec{r}(q^1)) |\vec{r}'(q^1)| dq^1 ,$$

with $\vec{r}(q_a^1)$, $\vec{r}(q_b^1)$ the extreme points of path γ .

Work

Integrals

$$\int_{\vec{r} \in \gamma} F(\vec{r}) \cdot \hat{t}(\vec{r})$$

implicitly mean

$$\int_{\vec{r} \in \gamma} F(\vec{r}) \cdot \hat{t}(\vec{r}) = \int_{\vec{r} \in \gamma} F(\vec{r}) \cdot \hat{t}(\vec{r}) |d\vec{r}| = \int_{\vec{r} \in \gamma} F(\vec{r}) \cdot d\vec{r} ,$$

as $\hat{t} = \frac{d\vec{r}}{|d\vec{r}|}$. Given a regular parametrization of the curve $\vec{r}(q^1)$ (with increasing q^1 so that $|dq^1| = dq^1$), and the differential $d\vec{r} = \vec{r}'(q^1) dq^1$, the integral can be written as an integral in the parameter q^1

$$\int_{q^1=q_a^1}^{q_b^1} F(\vec{r}(q^1)) \cdot \vec{r}'(q^1) dq^1$$

7.4.2 Surface integrals

Given two coordinates q^1, q^2 describing a surface, $\vec{r}(q^1, q^2)$ the elementary surface with unit normal reads

$$\hat{n} dS = d\vec{r}_1 \times d\vec{r}_2 = \frac{\partial \vec{r}}{\partial q^1} \times \frac{\partial \vec{r}}{\partial q^2} dq^1 dq^2 ,$$

and the elementary surface thus reads

$$|dS| = |\hat{n} dS| = \left| \frac{\partial \vec{r}}{\partial q^1} \times \frac{\partial \vec{r}}{\partial q^2} dq^1 dq^2 \right|$$

Density

Integrals

$$\int_{\vec{r} \in S} F(\vec{r})$$

implicitly mean

$$\int_{\vec{r} \in S} F(\vec{r}) = \int_{\vec{r} \in S} F(\vec{r}) |dS| .$$

Given regular parametrization of the surface, $\vec{r}(q^1, q^2)$, $(q^1, q^2) \in Q^{12}$, the integral can be written as the multi-dimensional integral in coordinates q^1, q^2 ,

$$\int_{\vec{r} \in S} F(\vec{r}) = \int_{(q^1, q^2) \in Q^{12}} F(\vec{r}(q^1, q^2)) \left| \frac{\partial \vec{r}}{\partial q^1} \times \frac{\partial \vec{r}}{\partial q^2} dq^1 dq^2 \right|$$

Flux

Integrals

$$\int_{\vec{r} \in S} \hat{n}(\vec{r}) \cdot F(\vec{r})$$

implicitly mean

$$\int_{\vec{r} \in S} \hat{n}(\vec{r}) \cdot F(\vec{r}) = \int_{\vec{r} \in S} \hat{n}(\vec{r}) \cdot F(\vec{r}) |dS|$$

Given regular parametrization of the surface, $\vec{r}(q^1, q^2)$, $(q^1, q^2) \in Q^{12}$, the integral can be written as the multi-dimensional integral in coordinates q^1, q^2 ,

$$\int_{\vec{r} \in S} \hat{n}(\vec{r}) \cdot F(\vec{r}) = \int_{(q^1, q^2) \in Q^{12}} \frac{\partial \vec{r}}{\partial q^1} \times \frac{\partial \vec{r}}{\partial q^2} \cdot F(\vec{r}(q^1, q^2)) dq^1 dq^2$$

7.4.3 Volume

$$dV = \frac{\partial \vec{r}}{\partial q^1} \cdot \frac{\partial \vec{r}}{\partial q^2} \times \frac{\partial \vec{r}}{\partial q^3} dq^1 dq^2 dq^3 .$$

Density

Integrals

$$\int_{\vec{r} \in V} F(\vec{r})$$

implicitly mean

$$\int_{\vec{r} \in V} F(\vec{r}) = \int_{\vec{r} \in V} F(\vec{r}) |dV| .$$

Given regular parametrization of the volume, $\vec{r}(q^1, q^2, q^3)$, $(q^1, q^2, q^3) \in Q$, the integral can be written as the multi-dimensional integral in coordinates q^1, q^2, q^3 ,

$$\int_{\vec{r} \in V} F(\vec{r}) |dV| = \int_{(q^1, q^2, q^3) \in Q} F(\vec{r}(q^1, q^2, q^3)) \left| \frac{\partial \vec{r}}{\partial q^1} \cdot \frac{\partial \vec{r}}{\partial q^2} \times \frac{\partial \vec{r}}{\partial q^3} dq^1 dq^2 dq^3 \right| .$$

7.4.4 Theorems

Gradient theorem

$$\int_V \nabla f = \oint_{\partial V} f \hat{n}$$

Divergence theorem

$$\int_V \nabla \cdot \vec{f} = \oint_{\partial V} \vec{f} \cdot \hat{n}$$

Curl theorem

$$\int_S [\nabla \times \vec{f}] \cdot \hat{n} = \oint_{\partial S} \vec{f} \cdot \hat{t}$$

7.5 Tensor Calculus in Euclidean Spaces - Cartesian coordinates in E^3

Using Cartesian coordinates $(q^1, q^2, q^3) = (r, \theta, z)$ and Cartesian base vectors (uniform in space, so that their derivatives are zero), a point in Euclidean vector space E^3 can be represented as

$$\vec{r} = x \hat{x} + y \hat{y} + z \hat{z} .$$

7.5.1 Natural basis, reciprocal basis, metric tensor, and Christoffel symbols

Cartesian coordinates in Euclidean spaces are a very special coordinate system, with reciprocal basis everywhere coinciding with natural basis, with uniform basis in space (zero second-order derivative of space w.r.t. coordinates, and thus zero first order derivative of base vectors, and thus identically zero Christoffel symbols), and components of the metric tensor equal to the identity matrix

$$\begin{cases} \vec{b}_1 = \vec{b}^1 = \hat{x} \\ \vec{b}_2 = \vec{b}^2 = \hat{y} \\ \vec{b}_3 = \vec{b}^3 = \hat{z} \end{cases}$$

$$[g_{ab}] = [g^{ab}] = \begin{bmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 1 \end{bmatrix}$$

$$\Gamma_{ab}^c = 0 \quad , \quad \forall a, b, c = 1 : 3 .$$

7.5.2 Differential operators

Gradient

Example 7.5.1 (Gradient of a scalar field)

$$\nabla F = \hat{x} \partial_x F + \hat{y} \partial_y F + \hat{z} \partial_z F_z$$

Example 7.5.2 (Gradient of a vector field)

$$\begin{aligned} \nabla F &= \nabla(F_x \hat{x} + F_y \hat{y} + F_z \hat{z}) = \\ &= \hat{x} \otimes \hat{x} \partial_x F_x + \hat{x} \otimes \hat{y} \partial_x F_y + \hat{x} \otimes \hat{z} \partial_x F_z + \\ &+ \hat{y} \otimes \hat{x} \partial_y F_x + \hat{y} \otimes \hat{y} \partial_y F_y + \hat{y} \otimes \hat{z} \partial_y F_z + \\ &+ \hat{z} \otimes \hat{x} \partial_z F_x + \hat{z} \otimes \hat{y} \partial_z F_y + \hat{z} \otimes \hat{z} \partial_z F_z \end{aligned}$$

Example 7.5.3 (Gradient of a 2^{nd} -order tensor field)

Directional derivative

Divergence

Example 7.5.4 (Divergence of a vector field)

$$\begin{aligned} \nabla \cdot F &= \nabla \cdot (F_x \hat{x} + F_y \hat{y} + F_z \hat{z}) = \\ &= \partial_x F_x + \partial_y F_y + \partial_z F_z . \end{aligned}$$

Example 7.5.5 (Divergence of a 2^{nd} -order tensor field)

$$\begin{aligned} \nabla \cdot F &= \nabla \cdot (F_{ab} \vec{e}_a \otimes \vec{e}_b) = \\ &= \vec{e}_c \frac{\partial F_{ab}}{\partial q^a} = \\ &= \hat{x} [\partial_x F_{xx} + \partial_y F_{yx} + \partial_z F_{zx}] + \\ &+ \hat{y} [\partial_x F_{xy} + \partial_y F_{yy} + \partial_z F_{zy}] + \\ &+ \hat{z} [\partial_x F_{xz} + \partial_y F_{yz} + \partial_z F_{zz}] . \end{aligned}$$

Laplacian

Example 7.5.6 (Laplacian of a scalar field)

$$\nabla^2 F = \partial_{xx} F + \partial_{yy} F + \partial_{zz} F$$

Example 7.5.7 (Laplacian of a vector field)

7.6 Tensor Calculus in Euclidean Spaces - cylindrical coordinates in E^3

7.6.1 Cylindrical coordiantes and cylindrical coordinates

Using cylindrical coordinates $(q^1, q^2, q^3) = (r, \theta, z)$ and cylindrical base vectors (uniform in space, so that their derivatives are zero), a point in Euclidean vector space E^3 can be represented as

$$\vec{r} = r \cos \theta \hat{x} + r \sin \theta \hat{y} + z \hat{z} .$$

7.6.2 Natural basis, reciprocal basis, metric tensor, and Christoffel symbols

Natural basis

Natural basis reads

$$\begin{cases} \vec{b}_1 = \frac{\partial \vec{r}}{\partial q^1} = \frac{\partial \vec{r}}{\partial r} = \cos \theta \hat{x} + \sin \theta \hat{y} \\ \vec{b}_2 = \frac{\partial \vec{r}}{\partial q^2} = \frac{\partial \vec{r}}{\partial \theta} = -r \sin \theta \hat{x} + r \cos \theta \hat{y} \\ \vec{b}_3 = \frac{\partial \vec{r}}{\partial q^3} = \frac{\partial \vec{r}}{\partial z} = \hat{z} \end{cases}$$

Metric tensor

Covariant components of metric tensors,

$$g_{ab} = \vec{b}_a \cdot \vec{b}_b ,$$

can be collected in the diagonal matrix

$$[g_{ab}] = \begin{bmatrix} 1 & 0 & 0 \\ 0 & r^2 & 0 \\ 0 & 0 & 1 \end{bmatrix} ,$$

while its contra-variant components can be collected in the inverse matrix (easy to compute, since $[g_{ab}]$ is diagonal),

$$[g^{ab}] = \begin{bmatrix} 1 & 0 & 0 \\ 0 & \frac{1}{r^2} & 0 \\ 0 & 0 & 1 \end{bmatrix} .$$

Reciprocal basis

Reciprocal basis is readily evaluated using $\vec{b}^a = g^{ab} \vec{b}_b$,

$$\begin{cases} \vec{b}^1 = \cos \theta \hat{x} + \sin \theta \hat{y} \\ \vec{b}^2 = -\frac{1}{r} \sin \theta \hat{x} + \frac{1}{r} \cos \theta \hat{y} \\ \vec{b}^3 = \hat{z} \end{cases}$$

Physical basis

Since metric tensor is diagonal, the cylindrical coordinate system is orthogonal, and its natural and reciprocal basis are orthogonal. A unit orthogonal basis, usually named **physical basis** with unit vector with no physical dimension, is evaluated by normalization process,

$$\begin{cases} \hat{r} = \hat{b}_1 = \frac{\vec{b}_1}{g_{11}} = \frac{\vec{b}^1}{g^{11}} = \cos \theta \hat{x} + \sin \theta \hat{y} \\ \hat{\theta} = \hat{b}_2 = \frac{\vec{b}_2}{g_{22}} = \frac{\vec{b}^2}{g^{22}} = -\sin \theta \hat{x} + \cos \theta \hat{y} \\ \hat{z} = \hat{b}_3 = \frac{\vec{b}_3}{g_{33}} = \frac{\vec{b}^3}{g^{33}} = \hat{z} . \end{cases}$$

Derivatives of natural basis and Christoffel symbols

Derivatives of the natural basis read

$$\begin{aligned} \frac{\partial \vec{b}_1}{\partial q^1} &= \vec{0} \\ \frac{\partial \vec{b}_2}{\partial q^2} &= -r \cos \theta \hat{x} - r \sin \theta \hat{y} = -q^1 \vec{b}_1 \\ \frac{\partial \vec{b}_3}{\partial q^3} &= \vec{0} \\ \frac{\partial \vec{b}_2}{\partial q^1} &= \frac{\partial \vec{b}_1}{\partial q^2} = -\sin \theta \hat{x} + \cos \theta \hat{y} = \frac{1}{q^1} \vec{b}_2 \\ \frac{\partial \vec{b}_3}{\partial q^1} &= \frac{\partial \vec{b}_1}{\partial q^3} = \vec{0} \\ \frac{\partial \vec{b}_3}{\partial q^2} &= \frac{\partial \vec{b}_2}{\partial q^3} = \vec{0} \end{aligned}$$

so that non-zero Christoffel symbols of a cylindrical coordinate system are

$$\begin{aligned} \Gamma_{12}^2 &= \Gamma_{21}^2 = \frac{1}{q^1} \\ \Gamma_{22}^1 &= -q^1 . \end{aligned}$$

7.6.3 Differential operators

Gradient

Example 7.6.1 (Gradient of a scalar field)

$$\begin{aligned}\nabla F &= \vec{b}^a \frac{\partial F}{\partial q^a} = \\ &= \hat{b}_a g^{aa} \frac{\partial F}{\partial q^a} = \\ &= \hat{r} \frac{\partial F}{\partial r} + \hat{\theta} \frac{1}{r} \frac{\partial F}{\partial \theta} + \hat{z} \frac{\partial F}{\partial z} .\end{aligned}$$

Example 7.6.2 (Gradient of a vector field)

$$\begin{aligned}\nabla F &= \vec{b}^a \otimes \vec{b}_b \left[\frac{\partial F^b}{\partial q^a} + \Gamma_{ac}^b F^c \right] = \\ &= \dots = \\ &= \vec{b}^1 \otimes \vec{b}_1 \partial_1 F^1 + \vec{b}^1 \otimes \vec{b}_2 [\partial_1 F^2 + \Gamma_{12}^2 F^2] + \vec{b}^1 \otimes \vec{b}_3 \partial_1 F^3 \\ &\quad + \vec{b}^2 \otimes \vec{b}_1 [\partial_2 F^1 + \Gamma_{22}^1 F^2] + \vec{b}^2 \otimes \vec{b}_2 [\partial_2 F^2 + \Gamma_{21}^2 F^1] + \vec{b}^2 \otimes \vec{b}_3 \partial_2 F^3 \\ &\quad + \vec{b}^3 \otimes \vec{b}_1 \partial_3 F^1 + \vec{b}^3 \otimes \vec{b}_2 \partial_3 F^2 + \vec{b}^3 \otimes \vec{b}_3 \partial_3 F^3 \\ &= \hat{r} \otimes \hat{r} \partial_r F_r + \hat{r} \otimes \hat{\theta} \frac{1}{r} [\partial_r (r F_\theta) + F_\theta] + \hat{r} \otimes \hat{z} \partial_r F_z \\ &\quad + \hat{\theta} \otimes \hat{r} \frac{1}{r} [\partial_\theta F_r - r F_\theta] + \hat{\theta} \otimes \hat{\theta} \left[\partial_\theta \left(\frac{F_\theta}{r} \right) + \frac{F_r}{r} \right] + \hat{\theta} \otimes \hat{z} \frac{1}{r} \partial_\theta F_z \\ &\quad + \hat{z} \otimes \hat{r} \partial_z F_x + \hat{z} \otimes \hat{\theta} \frac{1}{r} \partial_\theta F_y + \hat{z} \otimes \hat{z} \partial_z F_z .\end{aligned}$$

Example 7.6.3 (Gradient of a 2^{nd} -order tensor field)

Directional derivative

Divergence

Example 7.6.4 (Divergence of a vector field)

$$\begin{aligned}\nabla \cdot \vec{F} &= \frac{\partial F^a}{\partial q^a} + \Gamma_{ac}^a F^c = \\ &= \frac{\partial F_r}{\partial r} + \frac{\partial}{\partial \theta} \left(\frac{F_\theta}{r} \right) + \frac{F_\theta}{r} + \frac{\partial F_z}{\partial z} .\end{aligned}$$

Example 7.6.5 (Divergence of a 2^{nd} -order tensor field)

Laplacian

Example 7.6.6 (Laplacian of a scalar field)

Example 7.6.7 (Laplacian of a vector field)

7.7 Tensor Calculus in Euclidean Spaces - Spherical coordinates in E^3

Using spherical coordinates $(q^1, q^2, q^3) = (r, \phi, \theta)$ and spherical base vectors (uniform in space, so that their derivatives are zero), a point in Euclidean vector space E^3 can be represented as

$$\vec{r} = r \cos \theta \sin \phi \hat{x} + r \sin \theta \sin \phi \hat{y} + r \cos \phi \hat{z}.$$

7.7.1 Natural basis, reciprocal basis, metric tensor, and Christoffel symbols

7.7.2 Differential operators

Gradient

Example 7.7.1 (Gradient of a scalar field)

Example 7.7.2 (Gradient of a vector field)

Example 7.7.3 (Gradient of a 2^{nd} -order tensor field)

Directional derivative

Divergence

Example 7.7.4 (Divergence of a vector field)

Example 7.7.5 (Divergence of a 2^{nd} -order tensor field)

Laplacian

Example 7.7.6 (Laplacian of a scalar field)

Example 7.7.7 (Laplacian of a vector field)

TIME DERIVATIVE OF INTEGRALS OVER MOVING DOMAINS

Some results about time derivatives over moving domains are collected here.

8.1 Volume density

Reynolds transport theorem. Given a volume $V(t)$ with boundary $\partial V(t)$, whose points $\vec{r} \in \partial V(t)$ have velocity \vec{v}_b ,

$$\frac{d}{dt} \int_{V(t)} f = \int_{V(t)} \frac{\partial f}{\partial t} + \oint_{\partial V(t)} f \vec{v}_b \cdot \hat{n}.$$

“Proof”

8.2 Flux across a surface

$$\frac{d}{dt} \int_{S(t)} \vec{f} \cdot \hat{n} = \int_{S(t)} \frac{\partial \vec{f}}{\partial t} \cdot \hat{n} + \int_{S(t)} \nabla \cdot \vec{f} \vec{v}_b \cdot \hat{n} - \int_{\partial S(t)} \vec{v}_b \times \vec{f} \cdot \hat{t}$$

“Proof”

8.3 Work line integral along a line

$$\frac{d}{dt} \int_{\ell(t)} \vec{f} \cdot \hat{t} = \int_{\ell(t)} \frac{\partial \vec{f}}{\partial t} \cdot \hat{t} + \int_{\ell(t)} \nabla \times \vec{f} \cdot \vec{v}_b \times \hat{t} + \vec{f}_B \cdot \vec{v}_B - \vec{f}_A \cdot \vec{v}_A$$

“Proof”

Part V

Functional Analysis

INTRODUCTION TO FUNCTIONAL ANALYSIS

- Lebesgue integral
- L^p , H^p function spaces
- Banach and Hilbert spaces

DISTRIBUTIONS (OR GENERALIZED FUNCTIONS)

...

10.1 Dirac's delta

Dirac's delta $\delta(x)$ is a distribution, or generalized function, with the following properties

1.

$$\int_D \delta(x - x_0) dx = 1 \quad \text{if } x_0 \in D$$

2.

$$\int_D f(x) \delta(x - x_0) dx = f(x_0) \quad \text{if } x_0 \in D$$

for $\forall f(x)$ "regular" **todo** *what does regular mean?*

10.1.1 Dirac's delta in terms of regular functions

Approximations ...

$$\delta(x) \sim r_\varepsilon(x) = \begin{cases} \frac{1}{\varepsilon} & x \in [-\frac{\varepsilon}{2}, \frac{\varepsilon}{2}] \\ 0 & \text{otherwise} \end{cases}$$

as

1. Unitarity

$$\int_{x=-\infty}^{\infty} r_\varepsilon(x - x_0) dx = \int_{x=x_0-\frac{\varepsilon}{2}}^{x_0+\frac{\varepsilon}{2}} \frac{1}{\varepsilon} dx = 1,$$

for $\forall \varepsilon$;

2. Shift property, using mean-value theorem of continuous functions

$$\int_{x=-\infty}^{\infty} r_\varepsilon(x - x_0) f(x) dx = \int_{x=x_0-\frac{\varepsilon}{2}}^{x_0+\frac{\varepsilon}{2}} \frac{1}{\varepsilon} f(x) dx = \frac{1}{\varepsilon} \varepsilon f(\xi),$$

with $\xi \in [x_0 - \frac{\varepsilon}{2}, x_0 + \frac{\varepsilon}{2}]$, for the mean value theorem. As $\varepsilon \rightarrow 0$, $\xi \rightarrow x_0$, and thus

$$\int_{x=-\infty}^{\infty} r_\varepsilon(x - x_0) f(x) dx \rightarrow f(x_0)$$

$$\delta(x) \sim t_\varepsilon(x) = \begin{cases} \frac{2}{\varepsilon} \left(1 - \frac{2|x|}{\varepsilon}\right) & x \in \left[-\frac{\varepsilon}{2}, \frac{\varepsilon}{2}\right] \\ 0 & \text{otherwise} \end{cases}$$

as

1. Unitarity

$$\int_{x=-\infty}^{\infty} t_\varepsilon(x - x_0) dx = \int_{x=x_0-\frac{\varepsilon}{2}}^{x_0+\frac{\varepsilon}{2}} \frac{2}{\varepsilon} \left(1 - \frac{2|x|}{\varepsilon}\right) dx = \frac{1}{2} \frac{2}{\varepsilon} = 1,$$

for $\forall \varepsilon$;

2. Shift property, using mean-value integration scheme in $x \in [x_0 - \frac{\varepsilon}{2}, x_0]$, $x \in [x_0, x_0 + \frac{\varepsilon}{2}]$ (**todo why?**)

$$\begin{aligned} \int_{x=-\infty}^{\infty} t_\varepsilon(x - x_0) f(x) dx &= \int_{x=x_0-\frac{\varepsilon}{2}}^{x_0+\frac{\varepsilon}{2}} \frac{2}{\varepsilon} \left(1 - \frac{2|x-x_0|}{\varepsilon}\right) f(x) dx = \\ &= \int_{x=x_0-\frac{\varepsilon}{2}}^{x_0} \frac{2}{\varepsilon} \left(1 - \frac{2|x-x_0|}{\varepsilon}\right) f(x) dx + \int_{x=x_0}^{x_0+\frac{\varepsilon}{2}} \frac{2}{\varepsilon} \left(1 - \frac{2|x-x_0|}{\varepsilon}\right) f(x) dx = \\ &= \frac{\varepsilon}{2} \frac{2}{\varepsilon} \left(1 - \frac{2\varepsilon}{\varepsilon 4}\right) f\left(x_0 - \frac{\varepsilon}{4}\right) dx + \frac{\varepsilon}{2} \frac{2}{\varepsilon} \left(1 - \frac{2\varepsilon}{\varepsilon 4}\right) f\left(x_0 + \frac{\varepsilon}{4}\right) dx = \\ &= \frac{1}{2} f\left(x_0 - \frac{\varepsilon}{4}\right) + \frac{1}{2} f\left(x_0 + \frac{\varepsilon}{4}\right) \end{aligned}$$

As $\varepsilon \rightarrow 0$

$$\int_{x=-\infty}^{\infty} t_\varepsilon(x - x_0) f(x) dx \rightarrow f(x_0)$$

Approximation 1. For $\alpha \rightarrow +\infty$,

$$\varphi_\alpha(x) = \sqrt{\frac{\alpha}{\pi}} e^{-\alpha x^2} \sim \delta(x)$$

Fourier transform of $\varphi_\alpha(x)$ reads

$$\begin{aligned} \mathcal{F}\{\varphi_\alpha(x)\}(k) &= \int_{x=-\infty}^{+\infty} \varphi_\alpha(x) e^{-ikx} dx = \\ &= \int_{x=-\infty}^{+\infty} \sqrt{\frac{\alpha}{\pi}} e^{-\alpha x^2} e^{-ikx} dx = \\ &= \sqrt{\frac{\alpha}{\pi}} \int_{x=-\infty}^{+\infty} e^{-\alpha(x+i\frac{k}{2\alpha})^2} dx e^{-\frac{k^2}{4\alpha}} = \\ &= \sqrt{\frac{\alpha}{\pi}} \sqrt{\frac{\pi}{\alpha}} e^{-\frac{k^2}{4\alpha}} = e^{-\frac{k^2}{4\alpha}}, \end{aligned}$$

for $\alpha \rightarrow +\infty$,

$$\mathcal{F}\{\varphi_\alpha(x)\}(k) \rightarrow 1$$

and thus $\varphi_\alpha(x) \rightarrow \delta(x)$ for $\alpha \rightarrow +\infty$.

Approximation 2. For $a \rightarrow +\infty$

$$\frac{1}{2\pi} \int_{k=-2\pi a}^{2\pi a} e^{ikx} dk = \int_{y=-a}^{+a} e^{i2\pi yx} dy \sim \delta(x)$$

or

$$\begin{aligned}\delta(x) &\sim \frac{1}{2\pi} \int_{k=-2\pi a}^{2\pi a} e^{ikx} dk = \frac{1}{2\pi} \left(\int_{k=-2\pi a}^0 e^{ikx} dk + \int_0^{k=2\pi a} e^{ikx} dk \right) = \frac{1}{2\pi} \int_{k=0}^{2\pi a} (e^{ikx} + e^{ikx}) dx = \frac{1}{\pi} \int_{x=0}^{2\pi a} \cos(kx) dk \\ &= \int_{y=-a}^{+a} e^{i2\pi yx} dy = \dots = \int_{y=0}^a (e^{i2\pi yx} + e^{i2\pi yx}) dy = 2 \int_{y=0}^a \cos(2\pi yx) dy .\end{aligned}$$

Approximation 3. For $a \rightarrow +\infty$

$$\frac{\sin(2\pi xa)}{\pi x} \sim \delta(x)$$

Directly follows from integral of approximation 2,

$$\int_{y=-a}^{+a} e^{i2\pi yx} dy = \frac{1}{i2\pi x} e^{i2\pi yx} \Big|_{y=-a}^{+a} = \frac{1}{\pi x} \frac{e^{i2\pi ax} - e^{-i2\pi ax}}{2i} = \frac{\sin(2\pi xa)}{\pi x}$$

Approximation 4. For $x \in [-\pi, \pi]$, and $N \rightarrow +\infty$

$$\frac{1}{2\pi} \sum_{n=-N}^N e^{inx} = \frac{1}{2\pi} \frac{\sin((N + \frac{1}{2})x)}{\sin(\frac{x}{2})} \sim \delta(x)$$

Integral $I = \int_{-\infty}^{+\infty} e^{-\alpha x^2} dx$

$$\begin{aligned}I^2 &= \int_{x=-\infty}^{+\infty} e^{-\alpha x^2} dx \int_{y=-\infty}^{+\infty} e^{-\alpha y^2} dy = \\ &= \int_{x=-\infty}^{+\infty} \int_{y=-\infty}^{+\infty} e^{-\alpha(x^2+y^2)} dx dy = \\ &= \int_{\theta=0}^{2\pi} \int_{r=0}^{+\infty} e^{-\alpha r^2} r dr d\theta = \\ &= 2\pi \frac{1}{2\alpha} \int_{r=0}^{+\infty} e^{-\alpha r^2} d(\alpha r^2) = \\ &= \frac{\pi}{\alpha} \left[-e^{-\alpha r^2} \right] \Big|_{r=0}^{+\infty} = \frac{\pi}{\alpha} .\end{aligned}$$

Part VI

Complex Calculus

COMPLEX ANALYSIS

11.1 Complex functions, $f : \mathbb{C} \rightarrow \mathbb{C}$

A complex function f of complex variable $z = x + iy$, $f : \mathbb{C} \rightarrow \mathbb{C}$, can be written as

$$f(z) = \tilde{u}(z) + i\tilde{v}(z) = u(x, y) + iv(x, y) ,$$

as the sum of its real part $u(z)$ and i times its imaginary part $v(x, y)$. Here $x, y \in \mathbb{R}$, while $\tilde{u}(z), \tilde{v}(z) : \mathbb{C} \rightarrow \mathbb{R}$ and $u(x, y), v(x, y) : \mathbb{R}^2 \rightarrow \mathbb{R}$. With some abuse of notation, tilde won't be always explicitly written when arguments of real and imaginary parts of f functions won't be written.

11.1.1 Limit

$$\lim_{z \rightarrow z_0} f(z) = f(z_0) \quad , \quad \forall \varepsilon > 0 \exists \delta > 0 \text{ s.t. } |f(z) - f(z_0)| < \delta \forall z \text{ s.t. } |z - z_0| < \varepsilon, z \neq z_0 .$$

11.1.2 Derivative

Using the definition of *limit of complex functions*, the derivative of a function $f : \mathbb{C} \rightarrow \mathbb{C}$, if it exists, is the limit of incremental ratio,

$$f'(z) = \lim_{\Delta z \rightarrow 0} \frac{f(z + \Delta z) - f(z)}{\Delta z} .$$

11.1.3 Line Integrals

Given a line $\gamma \in \mathbb{C}$, whose parametric form is $z(s)$, with regular parametrization with parameter $s \in [s_0, s_1]$,

$$\int_{\gamma} f(z) dz = \int_{s=s_0}^{s_1} f(z(s)) z'(s) ds .$$

11.2 Holomorphic Functions - Analytic Functions

Definition 11.2.1

A holomorphic function is a function whose *derivative* exists.

Examples of analytic functions. *todo...*

11.2.1 Cauchy-Riemann conditions

For a holomorphic function $f(z) = u(x, y) + iv(x, y)$, Cauchy-Riemann conditions

$$\begin{cases} u_{/x} = v_{/y} \\ u_{/y} = -v_{/x} \end{cases}$$

hold. The evaluation of the derivative once with $\Delta z = \Delta x$ and once with $\Delta z = i\Delta y$

$$\begin{aligned} f'(z) &= \lim_{\Delta z \rightarrow 0} \frac{f(z + \Delta z) - f(z)}{\Delta z} = \\ &= \begin{cases} \lim_{\Delta x \rightarrow 0} \frac{f(x + \Delta x, y) - f(x, y)}{\Delta x} = \lim_{\Delta x \rightarrow 0} \frac{u(x + \Delta x, y) + iv(x + \Delta x, y) - u(x, y) - iv(x, y)}{\Delta x} = u_{/x} + iv_{/x} \\ \lim_{\Delta y \rightarrow 0} \frac{f(x, y + \Delta y) - f(x, y)}{i\Delta y} = \lim_{\Delta y \rightarrow 0} \frac{u(x, y + \Delta y) + iv(x, y + \Delta y) - u(x, y) - iv(x, y)}{i\Delta y} = -iu_{/y} + v_{/y} \end{cases} \end{aligned}$$

provides the proof.

11.2.2 Cauchy Theorem

For a holomorphic function $f, f : \Omega \subseteq \mathbb{C} \rightarrow \mathbb{C}$

$$\oint_{\gamma} f(z) dz = 0 ,$$

for $\forall \gamma \subset \Omega$. Proof follows from *Green's lemma*, and *Cauchy-Riemann conditions*

$$\begin{aligned} \oint_{\gamma} f(z) dz &= \oint_{\gamma} (u(x, y) + iv(x, y)) (dx + idy) = \\ &= \oint_{\gamma} (u dx - v dy) + i \oint_{\gamma} (u dy + v dx) = \\ &= - \int_S \left(\underbrace{u_{/y} + v_{/x}}_{=0} \right) dx dy + i \int_S \left(\underbrace{u_{/x} - v_{/y}}_{=0} \right) dx dy = 0 . \end{aligned}$$

11.3 Useful integrals

11.3.1 Independence of line integral for holomorphic functions

For a function $f(z)$ analytic in D , the line integral on paths $\ell_{ab,i}$ with the same extreme points a, b contained in D is independent on the path, but only depends on the extreme points a, b ,

$$\int_{\ell_{ab,1}} f(z) dz = \int_{\ell_{ab,2}} f(z) dz$$

The proof readily follows, using [Cauchy theorem](#) applied to a function $f(z) : D \subseteq \mathbb{C} \rightarrow \mathbb{C}$, analytic in D , and splitting the closed path γ into two paths ℓ_1, ℓ_2 with the same extreme points, $\gamma = \ell_1 \cup (-\ell_2)$

$$0 = \oint_{\gamma} f(z) dz = \int_{\ell_1} f(z) dz + \int_{-\ell_2} f(z) dz = \int_{\ell_1} f(z) dz - \int_{\ell_2} f(z) dz.$$

11.3.2 Sum and difference of line integrals

11.3.3 Integral of z^n

Given a path γ embracing $z = 0$ only once in counter-clockwise direction, and $n \in \mathbb{Z}$

$$\oint_{\gamma} z^n dz = \begin{cases} 2\pi i & \text{if } n = -1 \\ 0 & \text{otherwise} \end{cases}$$

Since z^n is analytic everywhere (**todo prove it!** *Add a section with proofs for common functions*) except for $z = 0$, it's possible to evaluate the integral on a circle with center $z = 0$ and radius R . Using polar expression of the complex numbers on the circle, $z = Re^{i\theta}$, $\theta \in [0, 2\pi]$, R const, the differential becomes $dz = iRe^{i\theta}d\theta$ and the integral

$$\begin{aligned} \oint_{\gamma} z^n dz &= \int_{\theta=0}^{2\pi} (Re^{i\theta})^n iRe^{i\theta}d\theta = \\ &= i \int_{\theta=0}^{2\pi} R^{n+1} e^{i(n+1)\theta} d\theta = \\ &= \begin{cases} \text{if } n = -1 & : i2\pi \\ \text{otherwise} & : iR^{n+1} \frac{1}{i(n+1)} e^{i(n+1)\theta} \Big|_{\theta=0}^{2\pi} = \frac{R^{n+1}}{n+1} (1-1) = 0 \end{cases} \end{aligned}$$

11.4 Meromorphic functions

Definition 11.4.1

A meromorphic function in a domain is a function holomorphic everywhere except for a (finite?) number of poles. **check**

11.4.1 Singularities

Definition 11.4.2 (Pole)

A pole of order n of a function $f(z)$ is a complex number a so that

$$f(z) = \frac{\phi(z)}{(z-a)^n},$$

with $\phi(z)$ holomorphic in $\phi(a) \neq 0$

Examples. ...

Definition 11.4.3 (Branch)

Examples. $f(z) = z^{\frac{1}{2}}$

Definition 11.4.4 (Removable singularities)

Example. $f(z) = \frac{\sin z}{z}$

Other irregularities.

11.4.2 Laurent Series

Given a function $f(z)$, in a disk $D_{a,\varepsilon} : 0 < |z-a| < \varepsilon$, its Laurent series centered in a is the convergent (to $f(z)$, **todo** which type of convergence?) series

$$f(z) \sim \sum_{n=-\infty}^{+\infty} a_n (z-a)^n, \quad (11.1)$$

with

$$a_n = \frac{1}{2\pi i} \int_{\gamma} f(z) (z-a)^{-(n+1)} dz \quad (11.2)$$

and γ embracing $z = a$ once counter-clockwise. Proof follows immediately inserting the expressions of the coefficients a_n and using the *integral of z^n* . Evaluating the integral (11.2) of the coefficients of the Laurent series, using (11.1) to replace $f(z)$ with its series

$$\begin{aligned} a_n &= \frac{1}{2\pi i} \oint_{\gamma} \sum_{m=-\infty}^{+\infty} a_m (z-a)^m (z-a)^{-(n+1)} dz = \\ &= \frac{1}{2\pi i} \oint_{\gamma} \sum_{m=-\infty}^{+\infty} a_m (z-a)^{m-n-1} dz = \\ &= \frac{1}{2\pi i} \oint_{\gamma} a_n z^{-1} dz = \\ &= a_n. \end{aligned}$$

todo Some freestyle with function and its convergent series...add some detail, and the meaning of convergence

11.4.3 Cauchy formula

For an analytic function $f(z)$,

$$f(a) = \frac{1}{2\pi i} \oint_{\gamma} \frac{f(z)}{z-a} dz$$

Proof readily follows using the *integral of z^n* on the Taylor series of $\frac{f(z)}{z-a}$ whose 0^{th} order term reads $f(a)$,

$$\frac{1}{2\pi i} \oint_{\gamma} \frac{f(a) + \sum_{m=1}^{+\infty} f'(a)(z-a)^m}{z-a} dz = \frac{1}{2\pi i} \oint_{\gamma} \frac{f(a)}{z-a} dz = f(a) \frac{2\pi i}{2\pi i} = f(a) .$$

11.4.4 Residues

Definition 11.4.5 (Residue)

The residue of function f in a , $\text{Res}(f, a)$ is a complex number R so that $f(z) - \frac{R}{(z-a)}$ has analytic antiderivative in a disk $D_{a,\varepsilon} : 0 < |z-a| < \varepsilon$.

todo Explain this definition. Couldn't be possible to use $\text{Res}(f, a) = \frac{1}{2\pi i} \oint_{\gamma} f(z) dz = a_{-1}$ instead?

Properties.

- If $f(z)$ is analytic in $D_{a,\varepsilon}$ and has a pole of order n in $z = a$, its Laurent series has $a_m = 0$ for $m < n$ and reads

$$f(z) = \sum_{m=-n}^{+\infty} a_m (z-a)^m , \quad (11.3)$$

with $a_{-n} \neq 0$. Since $f(z)$ has a pole of order n in $z = a$, it can be written as

$$f(z) = \frac{\phi(z)}{(z-a)^n} ,$$

with $\phi(z)$ analytic in $D_{a,\varepsilon}$ and $\phi(a) \neq 0$. Since $\phi(z)$ is analytic, it has a Taylor series (or a Laurent series with non-negative powers),

$$\phi(z) \sim \sum_{m=0}^{+\infty} b_m (z-a)^m ,$$

(todo prove it! Extension of the real case. Add a link to the proof) and thus

$$f(z) \sim \sum_{m=0}^{+\infty} b_m (z-a)^{m-n} = \sum_{m=-n}^{+\infty} b_{m+n} (z-a)^m = \sum_{m=-n}^{+\infty} a_m (z-a)^m ,$$

with $a_m = b_{m+n}$.

- For simple closed path γ (embracing a only once counter-clockwise) in $D_{a,\varepsilon}$,

$$\oint_{\gamma} f(z) dz = 2\pi i a_{-1} = 2\pi i \text{Res}(f, a) \quad (11.4)$$

The proof readily follows, using the *integral of z^n* and Laurent series (11.1) of $f(z)$,

$$\oint_{\gamma} f(z) dz = \oint_{\gamma} \sum_{m=-\infty}^{+\infty} a_m (z-a)^m dz = 2\pi i a_{-1} .$$

- For a pole a of order n , the following holds

$$a_{-1} = \frac{1}{(n+1)!} \lim_{z \rightarrow a} \frac{d^{n-1}}{dz^{n-1}} [(z-a)^n f(z)]$$

The proof follows using Laurent series `{eq}\`eq:laurent:pole-n` for a function with pole of order n , and evaluating the $(n-1)^{th}$ order derivative

$$\begin{aligned} \frac{d^{n-1}}{dz^{n-1}} [(z-a)^n f(z)] &= \frac{d^{n-1}}{dz^{n-1}} \left[(z-a)^n \sum_{m=-n}^{+\infty} a_m (z-a)^m \right] = \\ &= \frac{d^{n-1}}{dz^{n-1}} \left[\sum_{m=-n}^{+\infty} a_m (z-a)^{m+n} \right] = \\ &= \frac{d^{n-1}}{dz^{n-1}} \left[\sum_{m=0}^{+\infty} a_{m-n} (z-a)^m \right] = \\ &= \frac{d^{n-2}}{dz^{n-2}} \left[\sum_{m=0}^{+\infty} m a_{m-n} (z-a)^{m-1} \right] = \\ &= \frac{d^{n-3}}{dz^{n-3}} \left[\sum_{m=0}^{+\infty} m(m-1) a_{m-n} (z-a)^{m-2} \right] = \\ &= \dots = \\ &= \left[\sum_{m=0}^{+\infty} m! a_{m-n} (z-a)^{m-n+1} \right] \end{aligned}$$

and then letting $z \rightarrow a$, so that only the term with $m-n+1=0$ survives

$$\lim_{z \rightarrow a} \frac{d^{n-1}}{dz^{n-1}} \left[(z-a)^n \sum_{m=-n}^{+\infty} a_m (z-a)^m \right] = (n-1)! a_{-1} .$$

11.4.5 Residue Theorem

Theorem 11.4.1 (Residue Theorem)

Given $f(z)$ with a finite number of poles $p_n \in D$, then

$$\int_{\gamma} f(z) dz = 2\pi i \sum_n I(\gamma, p_n) \text{Res}(f, p_n) ,$$

being γ a path in D , and $I(\gamma, p_n)$ the winding index of the path γ around pole p_n (+1 for each counter-clockwise loop, -1 for each clockwise loop).

The proof readily follows extending the result for a single pole (11.4) to general number of poles and general paths γ embracing (with sign) each pole p_n $I(\gamma, p_n)$ times, with the same techniques shown in section *Sum and difference of line integrals*.

11.4.6 Evaluation of integrals

11.4.7 Inverse Laplace Transform

Given Laplace transform

$$F(s) := \mathcal{L}\{f(t)\}(s) := \int_{t=0^-}^{+\infty} f(t)e^{-st} dt ,$$

the inverse transform can be evaluated as

$$f(t) = \mathcal{L}^{-1}\{F(s)\}(t) := \lim_{T \rightarrow +\infty} \frac{1}{2\pi i} \int_{s=a-iT}^{a+iT} e^{st} F(s) ds ,$$

with $a > \operatorname{Re}\{p_n\}$ (**todo** why?) for each pole of the function $F(s)$, evaluated on the vertical line $s = a + iy$, $y \in [-T, T]$, $ds = i dy$,

$$\begin{aligned} \lim_{T \rightarrow +\infty} \frac{1}{2\pi i} \int_{s=a-iT}^{a+iT} e^{st} F(s) ds &= \lim_{T \rightarrow +\infty} \frac{1}{2\pi i} \int_{s=a-iT}^{a+iT} e^{st} \int_{\tau=0^-}^{+\infty} f(\tau) e^{-s\tau} d\tau ds = \\ &= \lim_{T \rightarrow +\infty} \frac{1}{2\pi i} \int_{y=-T}^T e^{(a+iy)t} \int_{\tau=0^-}^{+\infty} f(\tau) e^{-(a+iy)\tau} d\tau i dy = \\ &= \lim_{T \rightarrow +\infty} \frac{1}{2\pi} \int_{y=-T}^T \int_{\tau=0^-}^{+\infty} e^{iy(t-\tau)} e^{a(t-\tau)} f(\tau) d\tau dy = \\ &= \dots \\ &= \int_{\tau=0^-}^{+\infty} \delta(t-\tau) e^{a(t-\tau)} f(\tau) d\tau = f(t) . \end{aligned}$$

having used the transform of *Dirac's delta* $\delta(t) = \frac{1}{2\pi} \int_{\omega=-\infty}^{+\infty} e^{-j\omega t} d\omega$.

todo Other approach: if $a > \operatorname{Re}\{p_n\}$, the contour built with the vertical line with real part a and the arc of circumference on its...

LAPLACE TRANSFORM

$$\mathcal{L}\{f(t)\}(s) := \int_{t=0^-}^{+\infty} e^{-st} f(t) dt = F(s) .$$

12.1 Inverse transform

$$f(t) = \mathcal{L}^{-1}\{F(s)\} = \dots$$

12.2 Properties

Linearity.

$$\mathcal{L}\{af(t) + bg(t)\}(s) = aF(s) + bG(s)$$

Dirac delta.

$$\mathcal{L}\{\delta(t)\} = \int_{t=0^-}^{+\infty} \delta(t) e^{st} dt = 1$$

Time delay. If $f(t) = 0$ for $t < 0$ (“causality”), for $\tau > 0$,

$$\mathcal{L}\{f(t - \tau)\}(s) = e^{-s\tau} F(s)$$

Proof readily follows direct computation with change of variable $z = t - \tau$, $dt = dz$

$$\mathcal{L}\{f(t - \tau)\}(s) = \int_{t=0^-}^{+\infty} f(t - \tau) e^{-st} dt = \int_{z=-\tau}^{+\infty} f(z) e^{-sz} dz e^{-s\tau} = \int_{z=0}^{+\infty} f(z) e^{-sz} dz e^{-s\tau} = e^{-s\tau} F(s) .$$

“Frequency shift”

$$\mathcal{L}\{f(t)e^{at}\}(s) = F(s - a)$$

Direct computation gives

$$\mathcal{L}\{f(t)e^{at}\}(s) = \int_{t=0^-}^{+\infty} f(t)e^{at}e^{-st} dt = \int_{t=0^-}^{+\infty} f(t)e^{-(s-a)t} dt = F(s - a)$$

Derivative.

$$\mathcal{L}\{f'(t)\}(s) = sF(s) - f(0^-) .$$

Proof readily follows direct computation, with integration by parts

$$\mathcal{L}\{f'(t)\}(s) = \int_{t=0^-}^{+\infty} f'(t)e^{-st} dt = [f(t)e^{-st}]_{t=0^-}^{+\infty} + s \int_{t=0^-}^{+\infty} f(t)e^{-st} dt = sF(s) - f(0^-),$$

provided that $\lim_{s \rightarrow +\infty} f(t)e^{-st} = 0$.

Integral.

$$\mathcal{L}\left\{\int_{\tau=0}^t f(\tau) d\tau\right\}(s) = \frac{1}{s}F(s).$$

Proof readily follows direct computation, with integration by parts

$$\mathcal{L}\left\{\int_{\tau=0^-}^t f(\tau) d\tau\right\}(s) = \int_{t=0^-}^{+\infty} \int_{\tau=0^-}^t f(\tau) d\tau e^{-st} dt = \left[-\frac{e^{-st}}{s} \int_{\tau=0^-}^t f(\tau) d\tau\right]_{t=0^-}^{+\infty} + \frac{1}{s} \int_{t=0^-}^{+\infty} f(t)e^{-st} dt = \frac{1}{s}F(s),$$

provided that $\int_{\tau=0^-}^0 f(\tau) d\tau = 0$ and $\lim_{t \rightarrow +\infty} \frac{e^{-st}}{s} \int_{\tau=0^-}^{+\infty} f(\tau) d\tau = 0$.

Convolution.

$$\begin{aligned} \mathcal{L}\{f(t) * g(t)\} &= \int_{t=0^-}^{+\infty} \int_{\tau=-\infty}^{+\infty} f(t-\tau)g(\tau) d\tau e^{-st} dt = \quad (1) \\ &= \int_{\tau=-\infty}^{+\infty} \int_{z=-\tau^-}^{+\infty} f(z)g(\tau) e^{-s(z+\tau)} d\tau dz = \quad (2) \\ &= \int_{z=0^-}^{+\infty} f(z) e^{-sz} dz \int_{\tau=0^-}^{+\infty} g(\tau) e^{-s\tau} d\tau = \\ &= \mathcal{L}\{f(t)\}(s) \mathcal{L}\{g(t)\}(s). \end{aligned} \quad (12.1)$$

having performed the change of coordinates $z = t - \tau$, $\tau = \tau$, with unitary Jacobian,

$$\frac{\partial(t, \tau)}{\partial(z, \tau)} = \partial_z t \partial_\tau \tau - \partial_z \tau \partial_\tau t = 1 \cdot 1 - 1 \cdot 0 = 1,$$

given the proper description of the domain of integration summarised in the extremes of integration in (1), and causality - i.e. all the functions $f(t)$ are identically zero for $t < 0$ - in (2).

Initial value. If ...

$$f(0^+) = \lim_{s \rightarrow +\infty} sF(s)$$

From direct computation,

$$\begin{aligned} \lim_{s \rightarrow +\infty} sF(s) &= \lim_{s \rightarrow +\infty} s \int_{t=0^-}^{+\infty} f(t) e^{-st} dt = \\ &= \lim_{s \rightarrow +\infty} \left\{ \left[s \left(-\frac{e^{-st}}{s} \right) f(t) \right]_{t=0^-}^{+\infty} + \int_{t=0^-}^{+\infty} e^{-st} f'(t) dt \right\} = \\ &= \lim_{s \rightarrow +\infty} \left\{ [-e^{-st} f(t)]_{t=0^-}^{+\infty} + \int_{t=0^-}^{+\infty} e^{-st} f'(t) dt \right\} = \\ &= f(0), \end{aligned}$$

provided that $\lim_{s \rightarrow +\infty} \lim_{t \rightarrow +\infty} e^{-st} f(t) = 0$ and $\lim_{s \rightarrow +\infty} \int_{t=0^-}^{+\infty} e^{-st} f'(t) dt = 0$.

Final value. If ...

$$f(+\infty) = \lim_{s \rightarrow 0} sF(s)$$

From direct computation (**todo** check and/or explain proof),

$$\begin{aligned} \lim_{s \rightarrow 0} sF(s) &= \lim_{s \rightarrow 0} s \int_{t=0}^{+\infty} f(t) e^{-st} dt = \\ &= \lim_{s \rightarrow 0} \left\{ \left[s \left(-\frac{e^{-st}}{s} \right) f(t) \right] \Big|_{t=0}^{+\infty} + \int_{t=0}^{+\infty} e^{-st} f'(t) dt \right\} = \\ &= \lim_{s \rightarrow 0} \left\{ [-e^{-st} f(t)] \Big|_{t=0}^{+\infty} + \int_{t=0}^{+\infty} e^{-st} f'(t) dt \right\} = \\ &= f(0) + f(+\infty) - f(0) = f(+\infty), \end{aligned}$$

provided that $\lim_{s \rightarrow 0} \lim_{t \rightarrow +\infty} e^{-st} f(t) = 0$.

FOURIER TRANSFORMS

- Fourier series: continuous time, periodic function in time
- Fourier transform: continuous time, non-periodic function in time
- Discrete Fourier transform (DFT):
- Discrete time Fourier transform (DTFT):

13.1 Fourier Series

For a T -periodic function,

$$g(t) \sim \frac{a_0}{2} + \sum_{n=1}^{+\infty} \left[a_n \cos \left(n \frac{2\pi}{T} t \right) + b_n \sin \left(n \frac{2\pi}{T} t \right) \right],$$

todo Prove it with properties of integrals of sin and cos over $t \in [0, T]$; prove convergence to average value at jumps

The exponential form reads

$$g(t) \sim \sum_{n=-\infty}^{+\infty} c_n e^{in \frac{2\pi}{T} t}, \quad (13.1)$$

where

$$c_n = \frac{1}{T} \int_{t=0}^T f(t) e^{-in \frac{2\pi}{T} t} dt. \quad (13.2)$$

Proof

Exploiting the properties of integrals of complex exponentials with $k \in \mathbb{Z}$

$$\int_{t=0}^T e^{ik \frac{2\pi}{T} t} dt = \begin{cases} \frac{1}{ik \frac{2\pi}{T}} \left[e^{ik \frac{2\pi}{T} t} \right]_{t=0}^T = 0 & \text{if } k \neq 0 \\ T & \text{if } k = 0 \end{cases}$$

$$\int_{t=0}^T f(t) e^{-im \frac{2\pi}{T} t} dt \sim \int_{t=0}^T \sum_{n=-\infty}^{+\infty} c_n e^{in \frac{2\pi}{T} t} e^{-im \frac{2\pi}{T} t} dt \sim \sum_{n=-\infty}^{+\infty} c_n \int_{t=0}^T e^{i(n-m) \frac{2\pi}{T} t} dt \sim T c_m.$$

13.2 Fourier Transform

$$\mathcal{F}\{g(t)\}(f) := \int_{t=-\infty}^{+\infty} g(t) e^{-i2\pi ft} dt.$$

13.2.1 Properties

Linearity.

Dirac delta.

$$\mathcal{L}\{\delta(t)\} = \int_{t=-\infty}^{+\infty} \delta(t) e^{-i2\pi ft} dt = 1$$

Time delay.

Derivative.

Integral.

Initial value.

Final value.

13.2.2 Inverse Fourier Transform

$$\mathcal{F}^{-1}\{G(f)\}(t) := \int_{f=-\infty}^{+\infty} G(f) e^{i2\pi ft} df.$$

Proof using Dirac's delta expression.

$$\begin{aligned} \mathcal{F}^{-1}\{G(f)\}(t) &:= \int_{f=-\infty}^{+\infty} G(f) e^{i2\pi ft} df = \int_{f=-\infty}^{+\infty} \int_{\tau=-\infty}^{+\infty} g(\tau) e^{-i2\pi f\tau} e^{i2\pi ft} d\tau df \\ &= \int_{f=-\infty}^{+\infty} \int_{\tau=-\infty}^{+\infty} g(\tau) e^{-i2\pi f\tau} e^{i2\pi ft} df d\tau = \\ &= \int_{f=-\infty}^{+\infty} \int_{\tau=-\infty}^{+\infty} g(\tau) e^{i2\pi f(t-\tau)} df d\tau = \\ &= \int_{\tau=-\infty}^{+\infty} g(\tau) \delta(t-\tau) d\tau = g(t). \end{aligned}$$

Proof. By the *dominated convergence theorem*, it follows that

$$\begin{aligned} \int_{\mathbb{R}} e^{i2\pi x\xi} F(\xi) d\xi &= \lim_{\varepsilon \rightarrow 0} \int_{\mathbb{R}} \underbrace{e^{-\pi\varepsilon^2\xi^2 + i2\pi x\xi}}_{G(\xi;x,\varepsilon)} F(\xi) d\xi = \\ &= \lim_{\varepsilon \rightarrow 0} \int_{\mathbb{R}} g(y;x,\varepsilon) f(y) dy = \\ &= \lim_{\varepsilon \rightarrow 0} \int_{\mathbb{R}} \varphi_{\varepsilon}(x-y) f(y) dy = \\ &= \int_{\mathbb{R}} \delta(x-y) f(y) dy = f(x) \end{aligned}$$

Lemma 1. The Fourier transform of function $\varphi(t) := e^{-\pi|t|^2}$ reads

$$\begin{aligned}\mathcal{F}\{\varphi(t)\}(\omega) &= \int_{t=-\infty}^{+\infty} \varphi(t) e^{-i\omega t} dt = \\ &= \int_{t=-\infty}^{+\infty} e^{-\pi|t|^2} e^{-i\omega t} dt = \\ &= \int_{t=-\infty}^{+\infty} e^{-\pi\left(t^2 + i\frac{\omega}{\pi}t - \frac{\omega^2}{4\pi^2}\right)} dt e^{-\frac{\omega^2}{4\pi^2}} = \\ &= \int_{t=-\infty}^{+\infty} e^{-\pi\left(t + i\frac{\omega}{2\pi}\right)^2} dt e^{-\frac{\omega^2}{4\pi^2}} = \\ &= e^{-\frac{\omega^2}{4\pi^2}},\end{aligned}$$

having evaluated *the integral* $\int_{-\infty}^{+\infty} e^{-\alpha x^2}$ with $\alpha = \pi$. **todo** justify the result for complex exponential. Use Bromwich contour integrals

Lemma 2. Fourier transform of $f(\alpha t)$, $\alpha > 0$

$$\mathcal{F}\{f(\alpha t)\}(\omega) = \int_{\mathbb{R}} f(\alpha t) e^{-j\omega t} dt = \int_{\tau \in \mathbb{R}} f(\tau) e^{-j\frac{\omega}{\alpha}\tau} d\tau \frac{1}{\alpha} = \frac{1}{\alpha} F\left(\frac{\omega}{\alpha}\right)$$

Lemma 3. $\frac{1}{\varepsilon} \varphi\left(\frac{t}{\varepsilon}\right) \rightarrow \delta(x)$ for $\varepsilon \rightarrow 0$

$$\mathcal{F}\left\{\frac{1}{\varepsilon} \varphi\left(\frac{t}{\varepsilon}\right)\right\}(\omega) = \frac{1}{\varepsilon} e^{-\frac{\omega^2}{4\pi\varepsilon^2}} = e^{-\frac{\omega^2}{4\pi\varepsilon^2}}$$

0. Fourier transform

$$G(f) = \int_{t=-\infty}^{\infty} e^{-i\omega t} g(t) dt$$

1.

$$g(t) = e^{i\alpha t} \psi(t)$$

$$\mathcal{F}\{g(t)\}(\omega) = \int_{t=-\infty}^{+\infty} g(t) e^{-i\omega t} dt = \int_{t=-\infty}^{+\infty} \psi(t) e^{i\alpha t} e^{-i\omega t} dt = \int_{t=-\infty}^{+\infty} \psi(t) e^{-i(\omega-\alpha)t} dt = \mathcal{F}\{\psi(t)\}(\omega - \alpha).$$

2.

$$\psi(t) = \phi(\alpha t)$$

$$\mathcal{F}\{\psi(t)\} = \int_{t=-\infty}^{+\infty} \psi(t) e^{-i\omega t} dt = \int_{t=-\infty}^{+\infty} \phi(\alpha t) e^{-i\omega t} dt = \int_{\tau=-\infty}^{+\infty} \phi(\tau) e^{-i\frac{\omega}{\alpha}\tau} \frac{d\tau}{\alpha} = \frac{1}{\alpha} \mathcal{F}\{\phi(t)\}\left(\frac{\omega}{\alpha}\right).$$

3. Fubini's theorem

4.

$$\varphi(t) := e^{-\pi t^2}$$

$$\mathcal{F}\{\varphi(t)\} = \int_{t=-\infty}^{+\infty} \varphi(t) e^{-i\omega t} dt = \int_{t=-\infty}^{+\infty} e^{-\pi t^2} e^{-i\omega t} dt$$

$$0 = \oint_{\gamma} e^{-\alpha|z|^2} dz = \int_{\dots} \dots$$

$$z = Re^{i\theta}, \quad dz = iRe^{i\theta} d\theta$$

$$\int_{C/4} e^{-\alpha|z|^2} dz = \int_{\theta=0}^{\frac{\pi}{2}} e^{-\alpha R^2} iRe^{i\theta} d\theta = iRe^{-\alpha R^2} \frac{e^{-i\theta}}{i} \Big|_{\theta=0}^{\frac{\pi}{2}}$$

$$\begin{aligned}\int_{t=0}^{+\infty} e^{-\pi t^2} e^{-i\omega t} dt &= \int_{t=0}^{+\infty} e^{-\left(\pi t^2 + i\omega t - \frac{\omega^2}{4\pi}\right)} dt e^{-\frac{\omega^2}{4\pi}} = \\ &= \int_{t=0}^{+\infty} e^{-\pi\left(t + i\frac{\omega}{2\pi}\right)^2} dt e^{-\frac{\omega^2}{4\pi}}\end{aligned}$$

5. $\varphi_\varepsilon(t) = \frac{1}{\varepsilon^n} \varphi\left(\frac{t}{\varepsilon}\right)$, $t \in \mathbb{R}^n$, is an approximation of Dirac's delta for $\varepsilon \rightarrow 0$, so that

$$\begin{aligned}\lim_{\varepsilon \rightarrow 0} \int_{t=-\infty}^{+\infty} \varphi_\varepsilon(t - \tau) f(t) dt &= f(\tau) \\ \lim_{\varepsilon \rightarrow 0} \int_{t=-\infty}^{+\infty} \varphi_\varepsilon(t) dt &= 1\end{aligned}$$

As the Fourier transform $\mathcal{F}\{\varphi_\varepsilon(t)\}(\omega) \rightarrow 1$ for $\varepsilon \rightarrow 0$, then $\varphi_\varepsilon(t) \rightarrow \delta(t)$.

13.3 Relations between Fourier transforms

Some freestyle in changing order of summations and integrals, and use of generalized functions here...check it!

13.3.1 Fourier transform of integrable functions

$$F(\nu) := \mathcal{F}\{f(t)\}(\nu) := \int_{t=-\infty}^{+\infty} f(t) e^{-i2\pi\nu t} dt,$$

13.3.2 Fourier transform of the sum of shifted integrable functions

The infinite sum of a shifted integrable function is defined as

$$\tilde{f}_T(t) = \sum_{n=-\infty}^{+\infty} f(t - nT).$$

Its Fourier transform reads

$$\begin{aligned}\mathcal{F}\{\tilde{f}_T(t)\}(\nu) &= \int_{t=-\infty}^{+\infty} \tilde{f}_T(t) e^{-i2\pi\nu t} dt = \\ &= \sum_{n=-\infty}^{+\infty} \int_{t=-\infty}^{+\infty} f(t - nT) e^{-i2\pi\nu t} dt = \quad (1)\end{aligned}$$

$$= \sum_{n=-\infty}^{+\infty} F(\nu) e^{-i2\pi\nu nT} = \quad (2)$$

$$\begin{aligned}&= F(\nu) \sum_{n=-\infty}^{+\infty} e^{-i2\pi\nu nT} = \quad (3) \\ &= \Delta\nu F(\nu) \text{III}_{\Delta\nu}(\nu),\end{aligned}$$

having used properties of Fourier transform of shifted function in (1), and the properties of Dirac's comb in (3), having defined the frequency resolution

$$\Delta\nu := \frac{1}{T}.$$

This Fourier transform is proportional to the Fourier transform of the original function, sampled in frequency with elementary frequency $\Delta\nu$.

13.3.3 Fourier transform of the a function sampled with a Dirac comb - DTFT

Fourier transform of the original function sampled with $\Delta t \text{III}_{\Delta t}(t)$ reads

$$\begin{aligned}
 \mathcal{F} \{ \Delta t f(t) \text{III}_{\Delta t}(t) \} &= \Delta t \int_{t=-\infty}^{+\infty} f(t) \text{III}_{\Delta t}(t) e^{-i2\pi\nu t} dt = \\
 &\sim \Delta t \frac{1}{\Delta t} \int_{t=-\infty}^{+\infty} f(t) \sum_{n=-\infty}^{+\infty} e^{in\frac{2\pi}{\Delta t}t} e^{-i2\pi\nu t} dt = \\
 &= \sum_{n=-\infty}^{+\infty} \int_{t=-\infty}^{+\infty} f(t) e^{-i2\pi(\nu - n\bar{\nu})t} dt = \\
 &= \sum_{n=-\infty}^{+\infty} F(\nu - n\bar{\nu}) = \text{DTFT}(f(t); \Delta t) ,
 \end{aligned} \tag{13.3}$$

i.e. equals the periodic sum of the Fourier of the original function, with period

$$\bar{\nu} := \frac{1}{\Delta t} .$$

From this last sentence and from the *symmetry properties of Fourier transform*, **Nyquist-Shannon sampling theorem** follows seamlessly.

Theorem 13.3.1 (Nyquist-Shannon sampling theorem)

In order to **avoid aliasing** the sampling frequency must be twice the maximum¹ frequency in the signal,

$$\nu_s \geq 2\nu_{max} .$$

todo check alternative expressions if using the definition of train of impulses instead of the Fourier series of Dirac's comb.

$$\begin{aligned}
 &= \Delta t \int_{t=-\infty}^{+\infty} f(t) \sum_{k=-\infty}^{+\infty} \delta(t - k\Delta t) e^{-i2\pi\nu t} dt = \\
 &= \Delta t \sum_{k=-\infty}^{+\infty} f(k\Delta t) e^{-i2\pi\nu k\Delta t} = \text{DTFT}(f(t); \Delta t)
 \end{aligned} \tag{13.4}$$

13.3.4 Fourier transform of the sum of shifted integral functions sampled with a Dirac comb

Fourier transform of the periodic sum

$$\Delta t \tilde{f}(t) \text{III}_{\Delta t}(t) = \Delta t \sum_{n=-\infty}^{+\infty} f(t - nT) \text{III}_{\Delta t}(t)$$

reads

$$\begin{aligned}
 \mathcal{F} \{ \Delta t \tilde{f}(t) \text{III}_{\Delta t}(t) \} (\nu) &= \Delta t \int_{t=-\infty}^{+\infty} \sum_{n=-\infty}^{+\infty} f(t - nT) \sum_{k=-\infty}^{+\infty} \delta(t - k\Delta t) e^{-i2\pi\nu t} dt = \\
 &= \Delta t \sum_{n=-\infty}^{+\infty} \sum_{k=-\infty}^{+\infty} f(k\Delta t - nT) e^{-i2\pi\nu k\Delta t} =
 \end{aligned}$$

¹ Usually there's no such a frequency above which the signal is exactly zero, but usually there's a frequency above which the spectrum of the signal is approximately zero, i.e. below a threshold where it can be treated as zero, and introduce no aliasing.

and defining $k\Delta\tau_n := k\Delta t - nT$,

$$\begin{aligned}
 &= \Delta t \sum_{n=-\infty}^{+\infty} \sum_{k=-\infty}^{+\infty} f(k\Delta\tau_n) e^{-i2\pi\nu k\Delta\tau_n} e^{-i2\pi\nu nT} = \\
 &= \Delta t \underbrace{\sum_{k=-\infty}^{+\infty} f(k\Delta\tau_n) e^{-i2\pi\nu k\Delta\tau_n}}_{=\text{DTFT}(f(t), \Delta t)} \underbrace{\sum_{n=-\infty}^{+\infty} e^{-i2\pi\nu nT}}_{=\Delta\nu \text{III}_{\Delta\nu}(\nu)} = \\
 &= \text{DTFT}(f(t), \Delta t) \Delta\nu \text{III}_{\Delta\nu}(\nu) .
 \end{aligned}$$

todo check! check the change of coordinates that makes DTFT appear

todo check! what follows or, using the relation between Δt and $T = N\Delta t$, $\Delta\nu = \frac{1}{T}$, and thus

$$\Delta t \Delta\nu = \Delta t \frac{1}{T} = \frac{1}{N} ,$$

it follows

$$= \frac{1}{N} \sum_{k=-\infty}^{+\infty} f(k\Delta\tau_n) e^{-i2\pi\nu k\Delta\tau_n} \text{III}_{\Delta\nu}(\nu) .$$

13.3.5 Useful properties

Dirac's comb $\text{III}_T(t)$

Dirac comb $\text{III}_T(t)$ is defined as a train of Dirac's delta

$$\text{III}_T(t) = \sum_{m=-\infty}^{+\infty} \delta(t - mT) .$$

Coefficients (13.2) of the Fourier series (13.1) of a T -periodic train of Dirac delta for $t \in [-\frac{T}{2}, \frac{T}{2}]$, read

$$c_n = \frac{1}{T} \int_{t=0}^T \delta(t) e^{-in\frac{2\pi}{T}t} = \frac{1}{T} ,$$

and thus the Fourier series of Dirac comb $\text{III}_T(t)$ reads

$$\text{III}_T(t) = \sum_{m=-\infty}^{+\infty} \delta(t - mT) \sim \frac{1}{T} \sum_{n=-\infty}^{+\infty} e^{in\frac{2\pi}{T}t} .$$

Symmetry of Fourier transform

Part VII

Calculus of Variations

INTRODUCTION TO CALCULUS OF VARIATIONS

Calculus of variation deals with variations - i.e. “small changes” - of functions and functionals.

The meaning of the term functional may vary on the subfield of interest. In the field of calculus of variation, a **functional** can be defined as a function of function, i.e. a function whose argument is another function.

Fields and applications

Fields and applications related to calculus of variations (give some examples below):

- gradient-based techniques like some methods in:
 - optimization, either free or constrained (via Lagrange multiplier methods)
 - sensitivity
- classical mechanics and physics in general:
 - analytical mechanics: [Lagrangian formulation](#) and [Hamiltonian formulation](#) of classical mechanics
- ...

Examples

- Lagrange equations for general problem
- examples:
 - brachistochrone for minimum time,...
 - catenary, i.e. static solution of wire and cables with negligible bending stiffness
 - isoperimetric inequality, i.e. circle is the plane closed curve with given perimeter enclosing the largest area
- sensitivity of results to parameters. Some interesting sensitivity, both in time and transformed domains
 - characteristics of a system:
 - * equilibria
 - * eigenvalues
 - * ...
- optimal control methods

14.1 Lagrange equations

Given the functional S , with arguments a function $q(t)$ and the independent variable t ,

$$S[q(t), t] = \int_{t=t_0}^{t_1} L(\dot{q}(t), q(t), t) dt$$

its variation w.r.t. the function $q(t)$ reads

$$\delta S[q(t), t] = \lim_{\varepsilon \rightarrow 0} \frac{1}{\varepsilon} (S[q(t) + \varepsilon w(t), t] - S[q(t), t])$$

where the function $w(t)$ is arbitrary, among those satisfying the constraint of the problems: as an example here, if the function $q(t)$ has prescribed values q^* for some values of the independent variable, t^* , the variation $w(t)$ of the function $q(t)$ is zero there, $w(t^*) = 0$ so that the varied function $q(t) + \varepsilon w(t)$ satisfies the constraint as well, i.e. $q(t^*) + \varepsilon w(t^*) = q^*$.

Variation involves only small changes of function arguments, since these ones are the elements that can be effectively changed, while the independent variable is not.

Direct computation of the variation gives

$$\begin{aligned} \delta S[q(t), t] &= \lim_{\varepsilon \rightarrow 0} \frac{1}{\varepsilon} (S[q(t) + \varepsilon w(t), t] - S[q(t), t]) = \\ &= \lim_{\varepsilon \rightarrow 0} \frac{1}{\varepsilon} \left(\int_{t=t_0}^{t_1} L(\dot{q}(t) + \varepsilon \dot{w}(t), q(t) + \varepsilon w(t), t) dt - \int_{t=t_0}^{t_1} L(\dot{q}(t), q(t), t) dt \right) = \\ &= \lim_{\varepsilon \rightarrow 0} \frac{1}{\varepsilon} \int_{t=t_0}^{t_1} (L(\dot{q}(t) + \varepsilon \dot{w}(t), q(t) + \varepsilon w(t), t) - L(\dot{q}(t), q(t), t)) dt = \\ &= \lim_{\varepsilon \rightarrow 0} \frac{1}{\varepsilon} \int_{t=t_0}^{t_1} \left\{ L(\dot{q}(t), q(t), t) + \varepsilon \left[\frac{\partial L}{\partial \dot{q}} \dot{w}(t) + \frac{\partial L}{\partial q} w(t) \right] + o(\varepsilon) - L(\dot{q}(t), q(t), t) \right\} dt = \\ &= \lim_{\varepsilon \rightarrow 0} \frac{1}{\varepsilon} \int_{t=t_0}^{t_1} \left\{ \varepsilon \left[\frac{\partial L}{\partial \dot{q}} \dot{w}(t) + \frac{\partial L}{\partial q} w(t) \right] + o(\varepsilon) \right\} dt = \\ &= \int_{t=t_0}^{t_1} \left\{ \frac{\partial L}{\partial \dot{q}} \dot{w}(t) + \frac{\partial L}{\partial q} w(t) \right\} dt = \\ &= \left[w(t) \frac{\partial L}{\partial \dot{q}} \right]_{t=t_0}^{t_1} + \int_{t=t_0}^{t_1} \left\{ -\frac{d}{dt} \left(\frac{\partial L}{\partial \dot{q}} \right) + \frac{\partial L}{\partial q} \right\} w(t) dt . \end{aligned}$$

The solution depends on the boundary conditions at the extreme points t_0, t_1 . **If** the value of the function $q(t)$ is prescribed in t_0 and t_1 , $q(t_0) = q_0$, $q(t_1) = q_1$, then its variation is zero, $w(t_0) = w(t_1) = 0$, for the reason that has been discussed above. The variation of the functional with prescribed boundary values of the argument function thus reads

$$\delta S[q(t), t] = \int_{t=t_0}^{t_1} \left\{ -\frac{d}{dt} \left(\frac{\partial L}{\partial \dot{q}} \right) + \frac{\partial L}{\partial q} \right\} \delta q(t) dt ,$$

having called $w(t) =: \delta q(t)$ to stress that is the variation of function $q(t)$. This notation - it's just notation, it has no special properties - could be useful if the functional depends on several arguments.

Stationary conditions, $\delta S = 0$. Stationary condition of the functional S implies that $\delta S = 0$ for all the possible variations of the argument function, $\forall \delta q(t)$. This condition implies that the integrand is identically zero, i.e. **Lagrange equations**,

$$\frac{d}{dt} \left(\frac{\partial L}{\partial \dot{q}} \right) - \frac{\partial L}{\partial q} = 0 ,$$

Higher-order derivatives

Method 1. If the Lagrangian function L depends on higher order derivatives,

$$L(q^{(n)}(t), q^{(n-1)}(t), \dots, q'(t), q(t), t)$$

it's possible to recast the problem defining the n -dimensional function, $\mathbf{q}(t)$,

$$\mathbf{q}(t) = (q^0(t), q^1(t), \dots, q^{n-1}(t)) := (q(t), q'(t), \dots, q^{(n-1)}(t)) .$$

With some abuse of notation in L , the functional S can be recasted as

$$\begin{aligned} S[q(t), t] &= \int_{t=t_0}^{t_1} L(q^{(n)}(t), \dots, q(t), t) dt = \\ &= \int_{t=t_0}^{t_1} L(\dot{\mathbf{q}}(t), \mathbf{q}(t), t) dt . \end{aligned}$$

todo Add constraints on components of $\mathbf{q}(t)$?

Repeating the computation, the variation of the functional reads

$$\delta S[\mathbf{q}(t), t] = \left[\delta \mathbf{q}^T(t) \frac{\partial L}{\partial \dot{\mathbf{q}}} \right]_{t=t_0}^{t_1} + \int_{t=t_0}^{t_1} \delta \mathbf{q}^T(t) \left\{ -\frac{d}{dt} \left(\frac{\partial L}{\partial \dot{\mathbf{q}}} \right) + \frac{\partial L}{\partial \mathbf{q}} \right\} dt .$$

Method 2. ...

14.1.1 Euler-Beltrami equation

If the Lagrangian function L is not an explicit function of the independent variable, $L(q'(x), q(x))$, Euler-Beltrami equation follows from the derivative of the Lagrangian,

$$\begin{aligned} \frac{dL}{dx} &= \frac{\partial L}{\partial q'} q''(x) + \frac{\partial L}{\partial q} q' = \\ &= \frac{\partial L}{\partial q'} q'' + \frac{d}{dx} \left(\frac{\partial L}{\partial q'} \right) q' = \\ &= \frac{d}{dx} \left(\frac{\partial L}{\partial q'} q' \right) , \end{aligned}$$

and thus

$$\frac{d}{dx} \left[L - q' \frac{\partial L}{\partial q'} \right] = 0 \quad \rightarrow \quad L - q' \frac{\partial L}{\partial q'} = C \quad \text{const.}$$

Note 1. While Lagrange equations are a set of N equations if the functional depends on N argument functions $q_k(t)$, $k = 1 : N$, Euler-Beltrami equation is an equation only. Indeed for multiple argument functions

$$\begin{aligned} \frac{dL}{dx} &= \frac{\partial L}{\partial q'_k} q''_k(x) + \frac{\partial L}{\partial q_k} q'_k = \\ &= \frac{\partial L}{\partial q'_k} q''_k + \frac{d}{dx} \left(\frac{\partial L}{\partial q'_k} \right) q'_k = \frac{d}{dx} \left(\frac{\partial L}{\partial q'_k} q'_k \right) , \end{aligned}$$

where Einstein's summation notation of repeated index is used. Euler-Beltrami thus reads

$$L(q'_l(x), q_l(x)) - q'_k(x) \frac{\partial L}{\partial q'_k}(q'_l(x), q_l(x)) = C .$$

Note 2. If the Lagrangian function is an explicit function of the independent variable x , $L(q'(x), q(x), x)$, it's not hard to realize that the derivative of the Lagrangian function, along with the use of the Lagrange equation, gives

$$\frac{d}{dx} \left[L - q' \frac{\partial L}{\partial q'} \right] = \frac{\partial L}{\partial x}.$$

Example 14.1.1 (Euler-Beltrami with $L(q'(x), q(x), x)$, Hamiltonian, energy and E.Noether)

Euler-Beltrami equation shows that if $L(q'(x), q(x))$, thus $L - q' \frac{\partial L}{\partial q'}$ is constant, (or an integral of motion in dynamics). In analytical mechanics (Lagrange mechanics, Hamiltonian mechanics), Lagrangian and Hamiltonian functions of a system read

$$\begin{aligned} L(\dot{q}_k(t), q_k(t), t) &= T(\dot{q}, q, t) + U(q, t) \\ H(p, q, t) &:= p_k \dot{q}_k - L = \dot{q}_k \frac{\partial L}{\partial \dot{q}_k} - L, \end{aligned}$$

having used the common definition of the generalized momenta $p_k := \frac{\partial L}{\partial \dot{q}_k}$. It should be immediate to realize that the Hamiltonian is just the quantity appearing in Euler-Beltrami equation (or in its “modified version” if $\partial_t L \neq 0$), and thus

$$\frac{dH}{dt} = \frac{\partial L}{\partial t}.$$

In mechanics, if $\partial_t L = 0$, the Hamiltonian is a constant of motion. In this case, it can be prove that the Hamiltonian is equal to the energy of the system.

Classical examples.

Example 14.1.2 (Brachistochrone)

Find the trajectory...

- Elementary length: $ds = v dt$
- Energy: $E(y) = \frac{1}{2}mv^2 - mgy + C$. Setting $E = 0$ at starting point, from rest, at $y_0 = 0$, it implies $C = 0$; thus $v = \sqrt{2gy}$
- $x(s), y(s)$,
- $ds = \sqrt{dx^2 + dy^2} = \sqrt{1 + y'^2(x)} dx$

$$T = \int_{t_0}^{t_1} dt = \int_{s_0}^{s_1} \frac{ds}{v} = \int_{x_0}^{x_1} \frac{\sqrt{1 + y'^2(x)}}{\sqrt{2gy(x)}} dx$$

The Lagrangian doesn't explicitly depend on x , thus Euler-Beltrami equation can be used. Partial derivative of the Lagrangian function w.r.t. q' reads

$$\frac{\partial L}{\partial y'} = \dots = \frac{1}{\sqrt{2gy} \sqrt{1 + y'^2}} y',$$

and thus Euler-Beltrami equation reads

$$C = L - q' \frac{\partial L}{\partial y'} = \frac{1 + y'^2 - y'^2}{\sqrt{2gy} \sqrt{1 + y'^2}} = \frac{1}{\sqrt{2gy} \sqrt{1 + y'^2}}$$

Squaring $2gC^2 = \frac{1}{y(1+y'^2)}$, it's possible to write

$$y(x) = \frac{1}{2gC^2(1 + y'^2(x))},$$

Making the substitution $y(x)' = \dots$

Example 14.1.3 (Catenary)

Example 14.1.4 (Isoperimetric problem)

Part VIII

Ordinary Differential Equations

INTRODUCTION TO ORDINARY DIFFERENTIAL EQUATIONS

LINEAR TIME-INVARIANT SYSTEMS

A linear time invariant system is governed by a linear ODE with constant coefficients. These equations can be recast as a first order system of ODEs,

$$\begin{cases} \dot{\mathbf{x}} = \mathbf{A}\mathbf{x} + \mathbf{B}\mathbf{u} \\ \mathbf{y} = \mathbf{C}\mathbf{x} + \mathbf{D}\mathbf{u} \\ \mathbf{x}(0^-) = \mathbf{x}_0 \end{cases}$$

Exploiting the *properties of matrix exponential* the general expression of the state can be written as the sum of the free response to initial condition and the forced response.

$$\begin{aligned} \mathbf{x}(t) &= e^{\mathbf{A}t}\mathbf{x}_0 + \int_{\tau=0^-}^t e^{\mathbf{A}(t-\tau)}\mathbf{B}\mathbf{u}(\tau) d\tau \\ \mathbf{y}(t) &= \mathbf{C}e^{\mathbf{A}t}\mathbf{x}_0 + \mathbf{C} \int_{\tau=0^-}^t e^{\mathbf{A}(t-\tau)}\mathbf{B}\mathbf{u}(\tau) d\tau + \mathbf{D}\mathbf{u}(t) \end{aligned}$$

Proof in time domain

Multiplying by $e^{-\mathbf{A}t}$,

$$\begin{aligned} e^{-\mathbf{A}t}(\dot{\mathbf{x}}(t) - \mathbf{A}\mathbf{x}(t)) &= e^{-\mathbf{A}t}\mathbf{B}\mathbf{u}(t) \\ \frac{d}{dt}(\mathbf{x}e^{-\mathbf{A}t}) &= e^{-\mathbf{A}t}\mathbf{B}\mathbf{u}(t) \end{aligned}$$

and integrating from 0^- to a generic time value t ,

$$e^{-\mathbf{A}t}\mathbf{x}(t) - \mathbf{x}_0 = \int_{\tau=0^-}^t e^{-\mathbf{A}\tau}\mathbf{B}\mathbf{u}(\tau) d\tau$$

The state $\mathbf{x}(t)$ can be written as the sum of the free response and a force response. The general expression of the state and the output as a function reads

$$\begin{aligned} \mathbf{x}(t) &= e^{\mathbf{A}t}\mathbf{x}_0 + \int_{\tau=0^-}^t e^{\mathbf{A}(t-\tau)}\mathbf{B}\mathbf{u}(\tau) d\tau \\ \mathbf{y}(t) &= \mathbf{C}e^{\mathbf{A}t}\mathbf{x}_0 + \mathbf{C} \int_{\tau=0^-}^t e^{\mathbf{A}(t-\tau)}\mathbf{B}\mathbf{u}(\tau) d\tau + \mathbf{D}\mathbf{u}(t) \end{aligned}$$

Laplace domain. The *Laplace transform* of the problem reads

$$\begin{cases} s\hat{\mathbf{x}} = \mathbf{A}\hat{\mathbf{x}} + \mathbf{B}\hat{\mathbf{u}} + \mathbf{x}_0 \\ \hat{\mathbf{y}} = \mathbf{C}\hat{\mathbf{x}} + \mathbf{D}\hat{\mathbf{u}} \end{cases}$$

$$\begin{aligned}
(s\mathbf{I} - \mathbf{A})\hat{\mathbf{x}} &= \mathbf{B}\hat{\mathbf{u}} + \mathbf{x}_0 \\
\hat{\mathbf{x}}(s) &= (s\mathbf{I} - \mathbf{A})^{-1}\mathbf{x}_0 + (s\mathbf{I} - \mathbf{A})^{-1}\mathbf{B}\hat{\mathbf{u}}(s) \\
\hat{\mathbf{y}}(s) &= \mathbf{C}(s\mathbf{I} - \mathbf{A})^{-1}\mathbf{x}_0 + [\mathbf{C}(s\mathbf{I} - \mathbf{A})^{-1}\mathbf{B} + \mathbf{D}]\hat{\mathbf{u}}(s)
\end{aligned}$$

Performing inverse Laplace transform allows to go back to time domain (just use Laplace inverse transform of a matrix exponential, and the formula (12.1) for Laplace transform of convolution).

16.1 Impulsive force

The effect of an impulsive force at time $t = 0$ is equivalent to an instantaneous change in the initial state, from time 0^- before the impulse to time 0^+ after the impulse. Splitting the input $\mathbf{u}(t)$ as the sum of impulsive input and regular input,

$$\begin{aligned}
\mathbf{u}(t) &= \mathbf{u}_r(t) + \mathbf{u}_\delta(t) \\
\hat{\mathbf{u}}(s) &= \hat{\mathbf{u}}_r(s) + \mathbf{u}_\delta
\end{aligned}$$

the solution in time and Laplace domain reads

$$\begin{aligned}
\mathbf{x}(t) &= e^{\mathbf{A}t}\mathbf{x}_0 + \int_{\tau=0^-}^t e^{\mathbf{A}(t-\tau)}\mathbf{B}(\mathbf{u}_r(\tau) + \mathbf{u}_\delta\delta(\tau)) d\tau = \\
&= e^{\mathbf{A}t}(\mathbf{x}_0 + \mathbf{B}\mathbf{u}_\delta) + \int_{\tau=0^-}^t e^{\mathbf{A}(t-\tau)}\mathbf{B}\mathbf{u}_r(\tau) d\tau \\
\mathbf{y}(t) &= \mathbf{C}e^{\mathbf{A}t}(\mathbf{x}_0 + \mathbf{B}\mathbf{u}_\delta) + \int_{\tau=0^-}^t \mathbf{C}e^{\mathbf{A}(t-\tau)}\mathbf{B}\mathbf{u}_r(\tau) d\tau + \mathbf{D}\mathbf{u}_r(t) + \mathbf{D}\mathbf{u}_\delta(t) \\
\hat{\mathbf{x}}(s) &= (s\mathbf{I} - \mathbf{A})^{-1}\mathbf{B}\hat{\mathbf{u}}_r(s) + (s\mathbf{I} - \mathbf{A})^{-1}(\mathbf{x}_0 + \mathbf{B}\mathbf{u}_\delta) \\
\hat{\mathbf{y}}(s) &= [\mathbf{C}(s\mathbf{I} - \mathbf{A})^{-1}\mathbf{B} + \mathbf{D}]\hat{\mathbf{u}}_r(s) + \mathbf{C}(s\mathbf{I} - \mathbf{A})^{-1}(\mathbf{x}_0 + \mathbf{B}\mathbf{u}_\delta) + \mathbf{D}\mathbf{u}_\delta
\end{aligned}$$

16.2 Properties

Matrix exponential.

$$e^{\mathbf{A}t} = \sum_{k=0}^{+\infty} \frac{\mathbf{A}^k t^k}{k!}.$$

Assuming it's possible swap derivative operator and summation (when?), it's possible to write

$$\frac{d}{dt}e^{\mathbf{A}t} = \frac{d}{dt} \sum_{k=0}^{+\infty} \frac{\mathbf{A}^k t^k}{k!} = \sum_{k=1}^{+\infty} k t^{k-1} \frac{\mathbf{A}^k t^{k-1}}{k!} = \mathbf{A}e^{\mathbf{A}t}.$$

Laplace transform of exponential matrix.

$$\begin{aligned}
\mathcal{L}\{e^{\mathbf{A}t}\}(s) &:= \int_{t=0^-}^{+\infty} e^{\mathbf{A}t} e^{-st} dt = \\
&= \int_{t=0^-}^{+\infty} e^{(-s\mathbf{I} + \mathbf{A})t} dt = \\
&= (-s\mathbf{I} + \mathbf{A})^{-1} e^{(-s\mathbf{I} + \mathbf{A})t} \Big|_{t=0^-}^{+\infty} = \\
&= (s\mathbf{I} - \mathbf{A})^{-1},
\end{aligned}$$

for all the values of s for which $-s\mathbf{I} + \mathbf{A}$ is asymptotically stable, i.e. has all the eigenvalues (thus, assuming that the matrix \mathbf{A} can be diagonalizable. What happens if not? Exploit other matrix decompositions to draw conclusions) with negative real parts, and thus for all the values of $s > \max \operatorname{re}\{s_k(\mathbf{A})\}$, as it's shown in [Example 16.2.1](#)

Example 16.2.1 (Asymptotic stability of a matrix \mathbf{A})

An $N \times N$ diagonalizable matrix \mathbf{A} ,

$$\mathbf{A}\mathbf{v}_k = \mathbf{v}_k s_k \quad (16.1)$$

has all the eigenvalues with negative real part, $\operatorname{re}\{s_k\} < 0, \forall k = 1 : N$.

The eigenvalues of a matrix $a\mathbf{I} + \mathbf{A}$ are $a + s_k$, while the eigenvectors are the same as those of the matrix \mathbf{A} . This can be easily proved adding $a\mathbf{I}\mathbf{v}_k$ to both sides of equation (16.1),

$$(a\mathbf{I} + \mathbf{A})\mathbf{v}_k = \mathbf{v}_k(a + s_k) .$$

Transform of the convolution.

Part IX

Partial Differential Equations

INTRODUCTION TO PARTIAL DIFFERENTIAL EQUATIONS

Partial differential equations usually comes from balance equations in **continuum mechanics**. Integral equations are the most general form of these equations, and an equivalent differential problem only exists if the fields involved in the equations are regular enough, for their derivatives to exist - and to apply theorems requiring some regularity of the functions.

Classical numerical methods:

- **FVM**: directly solves the **integral problem**, solving integral balance equations for cells in which the domain is divided
- **FDM**: given the problem in **differential form**, FDM directly approximates space derivatives of the **strong formulation** of the problem
- **FEM**: given the problem in **differential form**, FEM projects the **weak formulation** of the problem on a finite-dimensional space
- **BEM**: *integro-differential equation, singularities,...*
- **Spectral methods**,...
- **SEM**,...

17.1 Examples

In Physics:

- Advection equation

$$\partial_t u + \vec{a} \cdot \nabla u = f$$

- Diffusion equation

$$\partial_t u - \nu \nabla^2 u = f$$

- Hyperbolic equation/system of equations

$$\partial_t \mathbf{u} + \nabla \cdot \mathbf{F}(\mathbf{u}) = \mathbf{f}$$

- Wave equation

$$\frac{1}{c^2} \partial_{tt} u - \nabla^2 u = f$$

17.2 Balance equations in physics

- Small-strain continuum mechanics

$$\rho \partial_{tt} \vec{s} = \rho_0 \vec{g} + \nabla \cdot \boldsymbol{\sigma}(\boldsymbol{\varepsilon})$$

- Heat conduction
- Fluid dynamics
 - Navier-Stokes for compressible fluids (conservative or convective equations)

{

- Navier-Stokes for incompressible fluids (convective form,...)

$$\begin{cases} \rho \partial_t \vec{u} + \rho (\vec{u} \cdot \nabla) \vec{u} - \mu \nabla^2 \vec{u} + \nabla P = \rho \vec{g} \\ \nabla \cdot \vec{u} = 0 \end{cases}$$

todo

- Different forms of equations may be more or less convenient for different solution approaches
- Most of the physical laws comes from integral balance equation of the form

$$\frac{d}{dt} \int_{V_t} \rho \mathbf{u} = \int_{V_t} \rho \mathbf{r} + \oint_{\partial V_t} \hat{n} \cdot \mathbf{T}(\mathbf{u})$$

whose local - differential - form (in case of differentiable functions) readily follows from the application of Reynolds' transport theorem and divergence theorem to transform time derivative and boundary terms

$$\begin{aligned} \partial_t (\rho \mathbf{u}) + \nabla \cdot (\rho \mathbf{u} \vec{u}) &= \rho \mathbf{r} + \nabla \cdot \mathbf{T}(\mathbf{u}) \\ \partial_t (\rho \mathbf{u}) + \nabla \cdot \mathbf{F}(\mathbf{u}) &= \rho \mathbf{r} , \end{aligned}$$

and the physical meaning of each term is evident and readily expalnable as flux or volume or surface sources.

- Further manipulation/simplification may cover the clear meaning of the terms of the differential equation. As an example, the conservative form of Navier-Stokes equations for incompressible fluids with constant and uniform density read

$$\begin{cases} \partial_t (\rho \vec{u}) + \nabla \cdot (\rho \vec{u} \otimes \vec{u}) = \rho \vec{g} + \nabla \cdot \mathbb{T} \\ \nabla \cdot \vec{u} = 0 , \end{cases}$$

where the stress tensor for a Newtonian fluid reads

$$\begin{aligned} \mathbb{T} &= -p \mathbb{I} + 2\mu \mathbb{D} + \lambda (\nabla \cdot \vec{u}) \mathbb{I} \\ &= -p \mathbb{I} + \mu (\nabla \vec{u} + \nabla^T \vec{u}) + \lambda (\nabla \cdot \vec{u}) \mathbb{I} \end{aligned}$$

Using the incompressibility constraint $\nabla \cdot \vec{u}$, and treating the density ρ as a constant and uniform parameter, the convective form of the Navier-Stokes equations reads

$$\begin{cases} \rho \partial_t \vec{u} + \rho (\vec{u} \cdot \nabla) \vec{u} = \rho \vec{g} - \nabla P + 2\mu \nabla \cdot \mathbb{D} \\ \nabla \cdot \vec{u} = 0 . \end{cases}$$

The divergence of the viscous stress tensor becomes

$$2\mu \nabla \cdot \mathbb{D} = \mu \nabla \cdot (\nabla \vec{u} + \nabla^T \vec{u}) = \mu \left(\nabla^2 \vec{u} + \underbrace{\nabla (\nabla \cdot \vec{u})}_{=0} \right) = \mu \nabla^2 \vec{u} ,$$

so that one of the most common form of incompressible Navier-Stokes equations follows

$$\begin{cases} \rho \partial_t \vec{u} + \rho(\vec{u} \cdot \nabla) \vec{u} - \mu \nabla^2 \vec{u} + \nabla P = \rho \vec{g} \\ \nabla \cdot \vec{u} = 0 . \end{cases}$$

It should be evident that in the latter form of Navier-Stokes equations no divergence explicitly appears, so that the right expression of surface source terms can't be found immediately. In momentum equation, surface source terms come from surface stress acting on the boundary of the domain, whose expression reads

$$\begin{aligned} \vec{t}_n &= \hat{n} \cdot \mathbb{T} = \\ &= \hat{n} \cdot (-P\mathbb{I} + 2\mu\mathbb{D}) = \\ &= \hat{n} \cdot (-P\mathbb{I} + \mu(\nabla\vec{u} + \nabla^T\vec{u})) = \\ &= -P\hat{n} + \hat{n} \cdot (\mu(\nabla\vec{u} + \nabla^T\vec{u})) = \end{aligned}$$

As an example, in weak formulation of incompressible Navier-Stokes problem the **natural boundary condition** arising in the method depends on the expression of the strong formulation of the NS problem. If one needs to prescribe stress boundary conditions, it could be an idea to start from NS equations w/o extra simplifications.

ELLIPTIC EQUATIONS

18.1 Poisson equation

Given the volume density source $f(\vec{r})$ and the diffusivity $\nu(\vec{r})$, Poisson equation for the scalar field $\phi(\vec{r})$ reads

$$-\nabla \cdot (\nu \nabla \phi) = f \quad \vec{r} \in V$$

with proper boundary conditions on ∂V . As an example, typical boundary conditions are:

$$\begin{aligned} \phi(\vec{r}) &= g(\vec{r}) & \vec{r} \in S_D & \text{essential - Dirichlet b.c.} \\ \nu \hat{n} \cdot \nabla \phi(\vec{r}) &= h(\vec{r}) & \vec{r} \in S_N & \text{natural - Neumann b.c.} \\ a\phi(\vec{r}) + \nu \hat{n} \cdot \nabla \phi(\vec{r}) &= b(\vec{r}) & \vec{r} \in S_R & \text{Robin b.c.} \end{aligned}$$

18.1.1 Weak formulation

For $\forall w \in \dots$ (functional space, recall some results about existence and uniqueness of the solution, Lax-Milgram theorem,...)

$$\begin{aligned} 0 &= \int_V w \{ \nabla \cdot (\nu \nabla \phi) + f \} = \\ &= \oint_{\partial V} w \hat{n} \cdot (\nu \nabla \phi) + \int_V \{ -\nu \nabla \vec{w} \cdot \nabla \phi + wf \} = \end{aligned}$$

Splitting boundary contribution as the sum from single contributions from different regions, and applying boundary conditions, setting $w = 0$ for $\vec{r} \in S_D$ (see the ways to prescribe essential boundary conditions),

$$0 = \int_{S_D=0} w \hat{n} \cdot (\nu \nabla \phi) + \int_{S_N} w \underbrace{\hat{n} \cdot (\nu \nabla \phi)}_{=h} + \int_{S_R} w \underbrace{\hat{n} \cdot (\nu \nabla \phi)}_{=b-a\phi} + \int_V \{ -\nu \nabla \vec{w} \cdot \nabla \phi + wf \} .$$

and rearranging the equation separating terms containing unknowns from known contributions,

$$\int_V \nu \nabla w \cdot \nabla \phi + \int_{S_R} wa\phi = \int_V wf + \int_{S_N} wh + \int_{S_R} wb \quad \forall w \in \dots ,$$

and $\phi = g$, for $\vec{r} \in S_D$.

Different ways to prescribe essential boundary conditions

Strong formulation.

Using Lagrange multiplier - weak formulation of essential boundary conditions. Adding a the essential boundary condition as a constraint with Lagrange multipliers in the weak formulation of the problem,

$$\cdots + \int_{S_D} w_D(\phi - g) ,$$

...

PARABOLIC EQUATIONS

19.1 Heat equation

Heat equation for a scalar field $\phi(\vec{r}, t)$ can be interpreted as the unsteady equation of a *Poisson equation*,

$$\partial_t \phi - \nabla \cdot (\nu \nabla \phi) = f \quad (\vec{r}, t) \in V \times [0, T] ,$$

with proper boundary and initial conditions, $\phi(\vec{r}, 0) = \phi_0(\vec{r})$. Common boundary conditions are the same as the one discussed for Poisson problem.

19.1.1 Weak formulation

For $\forall w \in \dots$ (functional space, recall some results about existence and uniqueness of the solution, Lax-Milgram theorem,...)

$$\begin{aligned} 0 &= \int_V w \{-\partial_t \phi + \nabla \cdot (\nu \nabla \phi) + f\} = \\ &= \oint_{\partial V} w \hat{n} \cdot (\nu \nabla \phi) + \int_V \{-\partial_t \phi - \nu \nabla \vec{w} \cdot \nabla \phi + wf\} = \end{aligned}$$

Splitting boundary contribution as the sum from single contributions from different regions, and applying boundary conditions, setting $w = 0$ for $\vec{r} \in S_D$ (see the ways to prescribe essential boundary conditions),

$$0 = \int_{S_D} \underbrace{w \hat{n} \cdot (\nu \nabla \phi)}_{=0} + \int_{S_N} \underbrace{w \hat{n} \cdot (\nu \nabla \phi)}_{=h} + \int_{S_R} \underbrace{w \hat{n} \cdot (\nu \nabla \phi)}_{=k-\phi} + \int_V \{-\partial_t \phi - \nu \nabla \vec{w} \cdot \nabla \phi + wf\} .$$

and rearranging the equation separating terms containing unknowns from known contributions,

$$\int_V w \partial_t \phi + \int_V \nu \nabla w \cdot \nabla \phi + \int_{S_R} w \phi = \int_V wf + \int_{S_N} wh + \int_{S_R} wk \quad \forall w \in \dots ,$$

and $\phi = g$, for $\vec{r} \in S_D$.

HYPERBOLIC PROBLEMS

Hyperbolic problems often come from a small-amplitude linearization, or as the non-diffusion (or inviscid) limit of a more general problem.

As a result of these simplification, these problems may experience **shocks** (i.e. discontinuity in the solution, where the differential equations stop to hold, and integral equations and jump conditions are required). **todo classification of discontinuities on the massflow across the surface**

The very nature of these problem also suggest methods for the solution or the analysis of these equations, like **characteristic method**.

20.1 Scalar linear

20.1.1 1-dimensional

$$\partial_t u(x, t) + a \partial_x u(x, t) = f(x, t)$$

Characteristic method. $U(t) = u(X(t), t)$, with the characteristic curves $X(t)$ defined as those curves where the PDE becomes a ODE. Evaluating the time derivative of the function $u(X(t), t)$, the hyperbolic equation can be recast as

$$\frac{dU}{dt} + \left[a(X(t), t) - \frac{dX}{dt} \right] \partial_x u = f(X(t), t) .$$

The equation of characteristic lines is

$$\frac{dX}{dt} = a(X(t), t) ,$$

and the PDE on characteristic line becomes the ODE

$$\frac{dU}{dt}(X(t), t) = f(X(t), t) .$$

20.2 Scalar non-linear

20.3 System linear

20.3.1 1-dimensional

$$\begin{aligned} \mathbf{u}(x, t) \\ \partial_t \mathbf{u} + \mathbf{A} \partial_x \mathbf{u} = \mathbf{f} \end{aligned}$$

Method of characteristics

Characteristics. $\mathbf{U}(t) = \mathbf{u}(X(t), t)$

$$\frac{d\mathbf{U}}{dt} - \frac{dX}{dt} \partial_x \mathbf{u} + \mathbf{A} \partial_x \mathbf{u} = \mathbf{f}$$

In order to get the equations of characteristic lines where PDE turns into ODEs, the eigenproblem

$$\mathbf{A} \partial_x \mathbf{u} = \frac{dX}{dt} \partial_x \mathbf{u} ,$$

holds. This problem has non trivial solution if $\frac{dX}{dt}$ and $\partial_x \mathbf{u}$ are pairs of eigenvalues and (right) eigenvectors of the array \mathbf{A} .

Diagonalization.

$$\mathbf{A} = \mathbf{R} \mathbf{\Lambda} \mathbf{L}$$

$$\mathbf{L} [\partial_t \mathbf{u} + \mathbf{R} \mathbf{\Lambda} \mathbf{L} \partial_x \mathbf{u}] = \mathbf{L} \mathbf{f}$$

Since $\mathbf{L} = \mathbf{R}^{-1}$, and defining the **characteristic variables** by $d\mathbf{q} = \mathbf{L} d\mathbf{u}$ - in linear problems matrix \mathbf{A} is constant, and so its spectral decomposition, and thus $\mathbf{q} = \mathbf{L} \mathbf{u}$ -, it's possible to recast the original problem in diagonal form

$$\partial_t \mathbf{q} + \mathbf{\Lambda} \partial_x \mathbf{q} = \mathbf{L} \mathbf{f}$$

$$\partial_t q_i + \Lambda_i \partial_x q_i = \sum_k L_{ik} f_k =: F_i .$$

Thus, on the i^{th} family of characteristic lines, $\frac{dX}{dt} = \lambda_i$, $Q_i(t) = q_i(x(t), t)$ evolves as

$$\frac{dQ_i}{dt} = F_i .$$

If $F_i = [\mathbf{L} \mathbf{f}]_i = 0$, the characteristic variable q_i is constant along the characteristic lines. Once the characteristic variables are determined, the conservative variables are evaluated as $\mathbf{u}(x, t) = \mathbf{R} \mathbf{q}(x, t)$.

Domain of influence and domain of dependence

Riemann problem

A Riemann problem is defined as the evolution of the initial state

$$\mathbf{u}(x, t_0) = \begin{cases} \mathbf{u}_a , & x < x_0 \\ \mathbf{u}_b , & x > x_0 \end{cases}$$

This problem is quite useful in quite a wide range of numerical methods for hyperbolic problems - Godunov schemes in Finite Volume Methods -, to evaluate the **boundary state** to be used numerical flux.

For linear problems, the matrix \mathbf{A} is constant and so it is its spectral decomposition, $\mathbf{A} = \mathbf{R} \mathbf{\Lambda} \mathbf{L}$, and the solution of a Riemann problem of an homogeneous linear hyperbolic system can be easily determined analytically with the method of characteristics,

Let's change the origin of space and time, so that the initial state is in $t = 0$, and the jump in the initial condition in $x = 0$. Each characteristic variable $q_k(x, t)$ is constant on its family of characteristic lines, $x = X_k(t) = x_{0,k} + \lambda_k t$.

$$q_k(x, t) = q_k(x_{0,k} + \lambda_k t, t) = q_k(x_{0,k}, 0) = q_k(x - \lambda_k t, 0) = L_{ki} u_j(x - \lambda_k t, 0) .$$

Thus, the solution in conservative variables $\mathbf{u}(x, t)$ in x at time t reads

$$\begin{aligned}\mathbf{u}(x, t) &= \mathbf{R}\mathbf{q}(x, t) \\ u_i(x, t) &= R_{ik}q_k(x, t) = R_{ik}q_k(x - \lambda_k t, 0) = R_{ik}L_{kj}u_j(x - \lambda_k t, 0)\end{aligned}$$

In a Riemann problem for a N -dimensional linear system the solution shows $N + 1$ homogeneous regions (at most, in general the same number as the number of the non-coincident eigenvalues $+1$), delimited by the characteristic lines with origin in the discontinuity. Sorting the eigenvalues in increasing order

$$\lambda_1 > \lambda_2 > \dots > \lambda_N ,$$

and defining the homogeneous regions

$$\begin{aligned}S_0 &: \frac{x}{t} \in (-\infty, \lambda_1) \\ S_1 &: \frac{x}{t} \in (\lambda_1, \lambda_2) \\ &\dots \\ S_i &: \frac{x}{t} \in (\lambda_i, \lambda_{i+1}) \\ &\dots \\ S_{N-1} &: \frac{x}{t} \in (\lambda_{N-1}, \lambda_N) \\ S_N &: \frac{x}{t} \in (\lambda_N, +\infty)\end{aligned}$$

the solution is in the S_i region is

$$u_i(x, t) = \sum_{\lambda_k > \frac{x}{t}} R_{ik}q_{a,k} + \sum_{\lambda_k < \frac{x}{t}} R_{ik}q_{b,k}$$

Example 20.3.1 (Linear(ized) P-system)

The linear(ized) P-system around a uniform reference state $\bar{\rho}, \bar{u}$ in convective form reads

$$\partial_t \begin{bmatrix} \rho \\ u \end{bmatrix} + \begin{bmatrix} \bar{u} & \bar{\rho} \\ \frac{a^2}{\bar{\rho}} & \bar{u} \end{bmatrix} \partial_x \begin{bmatrix} \rho \\ u \end{bmatrix} = \mathbf{0} .$$

Spectral decomposition.

$$\begin{aligned}0 &= |-\lambda \mathbf{I} + \mathbf{A}| = (\bar{u} - \lambda)^2 - a^2 \\ \lambda_{12} &= \bar{u} \mp a \quad , \quad \mathbf{r}_{12} = \begin{bmatrix} \bar{\rho} \\ \mp a \end{bmatrix} \\ \mathbf{R} &= \begin{bmatrix} \bar{\rho} & \bar{\rho} \\ -a & a \end{bmatrix} \\ \mathbf{L} = \mathbf{R}^{-1} &= \frac{1}{2\bar{\rho}a} \begin{bmatrix} a & -\bar{\rho} \\ a & \bar{\rho} \end{bmatrix}\end{aligned}$$

Reference state.

$$|u| : \begin{cases} = 0 & \text{at rest} \\ < a & \text{subsonic flow} \\ > a & \text{supersonic flow to the left/right} \end{cases}$$

Subsonic: the two families of characteristic lines have opposite direction; supersonic: the two families of characteristic lines have the same direction.

Example 20.3.2 (Linearized shallow water equations)

Example 20.3.3 (Linearized Euler equations (acoustics))

Example 20.3.4 (Wave equation)

A wave equation arises in many different fields of science. As an example, 1-dimensional wave equation describes the axial dynamics of a truss

$$m\partial_{tt}u - EA\partial_{xx}u = f ,$$

that can be recast in the general expression of wave equation

$$\partial_{tt}u - c^2\partial_{xx}u = F$$

The 2nd order differential operator appearing in 1-dimensional wave equation can be factored as the “product” of 2 1st order differential operators,

$$(\partial_{tt} - c^2\partial_{xx})u = (\partial_t - c\partial_x)(\partial_t + c\partial_x)u$$

and thus a wave equation can be written as

$$\begin{cases} \partial_t u + c\partial_x u - w = 0 \\ \partial_t w - c\partial_x w = F \end{cases}$$

In the regime of small displacement, the velocity field is the partial time derivative of the displacement field, $v = \partial_t u$, and the axial force reads $N = EA\partial_x u$. Exploiting Schwartz’s theorem about mixed partial derivatives to write $\partial_t N = EA\partial_x v$, it’s possible to write the wave function as the following system of hyperbolic equations in the physical unknowns v, N

$$\begin{cases} \partial_t N - EA\partial_x v = 0 \\ \partial_t v - \frac{1}{m}\partial_x N = f \end{cases}$$

P-system and wave equation - reference state at rest, $\bar{u} = 0$.

$$\begin{cases} \partial_t \rho + \bar{\rho}\partial_x u = 0 \\ \partial_t u + \frac{a^2}{\bar{\rho}}\partial_x \rho = 0 \end{cases}$$

Taking time partial derivative of the first and space partial derivative of the second equation times $\bar{\rho}$, and evaluating their difference, a wave equation for *rho* appears

$$\partial_{tt}\rho - a^2\partial_{xx}\rho = 0 .$$

Analogously, taking space derivative of the first and time derivative of the second, a wave equation for the velocity field appears

$$\partial_{tt}u - a^2\partial_{xx}u = 0 .$$

20.4 System non-linear

20.4.1 1-dimensional space

$$\mathbf{u}(x, t)$$

$$\partial_t \mathbf{u} + \partial_x \mathbf{F}(\mathbf{u}) = \mathbf{f} \quad (\text{conservative form})$$

$$\partial_t \mathbf{u} + \partial_u \mathbf{F}(\mathbf{u}) \partial_x \mathbf{u} = \mathbf{f} \quad (\text{convective form})$$

20.5 n-dimensional space

$$\mathbf{u}(\vec{r}, t)$$

$$\partial_t \mathbf{u} + \nabla \cdot \mathbf{F}(\mathbf{u}) = \mathbf{f} \quad (\text{conservative form})$$

$$\partial_t \mathbf{u} + \nabla \mathbf{u} \cdot \partial_u \mathbf{F}(\mathbf{u}) = \mathbf{f} \quad (\text{convective form})$$

Different descriptions of integral problem,

$$\frac{d}{dt} \int_V \mathbf{u} + \oint_{\partial V} \hat{n} \cdot \mathbf{F}(\mathbf{u}) = \int_V \mathbf{f} \quad (\text{Eulerian})$$

$$\frac{d}{dt} \int_{V_t} \mathbf{u} - \oint_{\partial V_t} \mathbf{u} \vec{u} \cdot \hat{n} + \oint_{\partial V_t} \hat{n} \cdot \mathbf{F}(\mathbf{u}) = \int_{V_t} \mathbf{f} \quad (\text{Lagrangian})$$

$$\frac{d}{dt} \int_{v_t} \mathbf{u} - \oint_{\partial v_t} \mathbf{u} \vec{u}_b \cdot \hat{n} + \oint_{\partial v_t} \hat{n} \cdot \mathbf{F}(\mathbf{u}) = \int_{v_t} \mathbf{f} \quad (\text{arbitrary})$$

todo in coordinates

$$\begin{aligned} f_i &= \partial_t u_i + \partial_{x_k} F_{ki}(u_l) = \\ &= \partial_t u_i + \partial_{x_k} u_m \partial_{u_m} F_{ki}(u_l) = \end{aligned}$$

Example 20.5.1 (P-system in 1-dimensional domain)

$$\begin{cases} \partial_t \rho + u \partial_x \rho + \rho \partial_x u = 0 \\ \rho \partial_t u + \rho u \partial_x u + \partial_x P = 0 \end{cases}$$

with $\partial_x P = a^2 \partial_x \rho$,

Convective form

$$\partial_t \begin{bmatrix} \rho \\ u \end{bmatrix} + \begin{bmatrix} u & \rho \\ \frac{a^2}{\rho} & u \end{bmatrix} \partial_x \begin{bmatrix} \rho \\ u \end{bmatrix} = \underline{0}.$$

Conservative form

$$\partial_t \begin{bmatrix} \rho \\ \rho u \end{bmatrix} + \partial_x \begin{bmatrix} \rho u \\ \rho u^2 + \rho a^2 \end{bmatrix} = \underline{0}.$$

Spectral decomposition of $\mathbf{A}(\mathbf{u})$ gives

$$0 = \left| \begin{bmatrix} u - s & \rho \\ \frac{a^2}{\rho} & u - s \end{bmatrix} \right| = (u - s)^2 - a^2$$

$$s_{1,2} = u \mp a$$

$$\mathbf{R} = \begin{bmatrix} \rho & \rho \\ a & -a \end{bmatrix}$$

$$\mathbf{L} = \frac{1}{2\rho a} \begin{bmatrix} a & \rho \\ a & -\rho \end{bmatrix}$$

Example 20.5.2 (Euler equations in 1-dimensional domain)

Conservative form

$$\partial_t \begin{bmatrix} \rho \\ \rho u \\ \rho e^t \end{bmatrix} + \partial_x \begin{bmatrix} \rho u \\ \rho u^2 + P \\ \rho u h^t \end{bmatrix} = \underline{0},$$

with $h^t = e^t + \frac{P}{\rho}$ and $e^t = e + \frac{u^2}{2}$, and the pressure field can be written as a function of the other thermodynamic variables. As an example, using conservative variables $(\rho, m, E^t) = (\rho, \rho u, \rho e^t) = (\rho, \rho u, \rho (e + \frac{u^2}{2}))$

$$P(\rho, e) = P\left(\rho, \frac{E^t}{\rho} - \frac{m^2}{2\rho^2}\right) = \Pi(\rho, m, E^t)$$

so that

$$\begin{aligned} \partial_\rho \Pi &= \partial_\rho P|_e + \partial_e P|_\rho \left(-\frac{E^t}{\rho^2} + \frac{m^2}{\rho^3}\right) = \\ &= \partial_\rho P|_e + \partial_e P|_\rho \left(-\frac{e^t}{\rho} + \frac{u^2}{\rho}\right) \\ &= c^2 - \frac{P}{\rho^2} \partial_e P|_\rho + \partial_e P|_\rho \left(-\frac{e^t}{\rho} + \frac{u^2}{\rho}\right) \\ &= c^2 + \partial_e P|_\rho \left(-\frac{h^t}{\rho} + \frac{u^2}{\rho}\right) \\ \partial_m \Pi &= \partial_e P|_\rho \left(-\frac{m}{\rho^2}\right) \\ \partial_{E^t} \Pi &= \partial_e P|_\rho \left(\frac{1}{\rho}\right) \end{aligned}$$

The speed of sound reads

$$\begin{aligned} c^2 &= \partial_\rho P|_s = \\ &= \partial_\rho P|_e + \partial_e P|_\rho \partial_\rho e|_s = \\ &= \partial_\rho P|_e + \frac{P}{\rho^2} \partial_e P|_\rho, \end{aligned}$$

Conservative form in conservative variables.

$$\partial_t \begin{bmatrix} \rho \\ m \\ E^t \end{bmatrix} + \partial_x \begin{bmatrix} m \\ \frac{m^2}{\rho} + \Pi(\rho, m, E^t) \\ \frac{m}{\rho} (E^t + \Pi(\rho, m, E^t)) \end{bmatrix} = \underline{0},$$

Convective form in conservative variables.

$$\partial_t \begin{bmatrix} \rho \\ m \\ E^t \end{bmatrix} + \partial_x \begin{bmatrix} 0 & 1 & 0 \\ -\frac{m^2}{\rho^2} + \partial_\rho \Pi & \frac{2m}{\rho} + \partial_m \Pi & \partial_{E^t} \Pi \\ -\frac{m}{\rho^2} (E^t + \Pi) + \frac{m}{\rho} \partial_\rho \Pi & \frac{1}{\rho} (E^t + \Pi) + \frac{m}{\rho} \partial_m \Pi & \frac{m}{\rho} (1 + \partial_{E^t} \Pi) \end{bmatrix} \partial_x \begin{bmatrix} \rho \\ m \\ E^t \end{bmatrix} = \underline{0},$$

Spectral decomposition of $\mathbf{A}(\mathbf{u})$

$$\begin{aligned}
0 &= \left| \begin{bmatrix} -s & 1 & 0 \\ -u^2 + \partial_\rho \Pi & 2u + \partial_m \Pi - s & \partial_{E^t} \Pi \\ -u \left(e^t + \frac{P}{\rho} \right) + u \partial_\rho \Pi & e^t + \frac{P}{\rho} + u \partial_m \Pi & u(1 + \partial_{E^t} \Pi) - s \end{bmatrix} \right| = \\
&= -s [(2u + \partial_m \Pi - s)(u(1 + \partial_{E^t} \Pi) - s) - \partial_{E^t} \Pi (h^t + u \partial_m \Pi)] + \\
&\quad - u h^t \partial_{E^t} \Pi + u \partial_\rho \Pi \partial_{E^t} \Pi + \\
&\quad + (u^2 - \partial_\rho \Pi)(u(1 + \partial_{E^t} \Pi) - s) = \\
&= -s^3 + \\
&\quad + s^2 (2u + \partial_m \Pi + u + u \partial_{E^t} \Pi) + \\
&\quad + s (-2u^2 - 2u^2 \partial_{E^t} \Pi - u \partial_m \Pi - u \partial_m \Pi \partial_{E^t} \Pi + \partial_{E^t} \Pi h^t + u \partial_{E^t} \Pi \partial_m \Pi - u^2 + \partial_\rho \Pi) + \\
&\quad + (-u h^t \partial_{E^t} \Pi + u \partial_\rho \Pi \partial_{E^t} \Pi + u^3 + u^3 \partial_{E^t} \Pi - u \partial_\rho \Pi - u \partial_\rho \Pi \partial_{E^t} \Pi) + \\
&= -s^3 + \\
&\quad + s^2 (3u + \partial_m \Pi + u \partial_{E^t} \Pi) + \\
&\quad + s (-3u^2 - 2u^2 \partial_{E^t} \Pi - u \partial_m \Pi + \partial_{E^t} \Pi h^t + \partial_\rho \Pi) + \\
&\quad + (u^3 - u h^t \partial_{E^t} \Pi + u^3 \partial_{E^t} \Pi - u \partial_\rho \Pi) = \\
&= -(s - u)^3 + (s - u)c^2 = \\
&= (s - u) [-(s - u)^2 + c^2]
\end{aligned}$$

being

$$\begin{aligned}
\partial_m \Pi + u \partial_{E^t} \Pi &= \left(-\frac{u}{\rho} + \frac{u}{\rho} \right) \partial_\rho P|_e = 0 \\
-2u^2 \partial_{E^t} \Pi - u \partial_m \Pi + \partial_{E^t} \Pi h^t + \partial_\rho \Pi &= -\frac{u^2}{\rho} \partial_\rho P|_e + \frac{1}{\rho} \partial_e P|_\rho h^t + \partial_\rho P|_e + \partial_e P|_\rho \left(-\frac{e^t}{\rho} + \frac{u^2}{\rho} \right) = \\
&= \partial_e P|_\rho \frac{P}{\rho^2} + \partial_\rho P|_e = \\
&= c^2 \\
-u \partial_\rho \Pi + u^3 \partial_{E^t} \Pi - u h^t \partial_{E^t} \Pi &= u \left(-\partial_\rho P|_e - \partial_e P|_\rho \left(-\frac{e^t}{\rho} + \frac{u^2}{\rho} \right) + \frac{u^2}{\rho} \partial_e P|_\rho - \frac{h^t}{\rho} \partial_e P|_\rho \right) \\
&= u \left(-\partial_\rho P|_e - \frac{P}{\rho^2} \partial_e P|_\rho \right) = \\
&= -uc^2 .
\end{aligned}$$

Thus,

$$\begin{aligned}
s_{1,3} &= u \mp c \quad , \quad s_2 = u \\
\mathbf{r}_{1,3} &= \begin{bmatrix} 1 \\ u \mp c \\ \dots \end{bmatrix} \hat{\rho} \quad , \quad \mathbf{r}_2 = \begin{bmatrix} \dots \\ 0 \\ \dots \end{bmatrix} \hat{\rho}
\end{aligned}$$

being

$$\begin{aligned}
\hat{E}^t \partial_{E^t} \Pi &= [u^2 - \partial_\rho \Pi + (-u \pm c - \partial_m \Pi)(u \mp c)] \hat{\rho} = \\
&= [u^2 - \partial_\rho \Pi - u^2 + \pm 2uc - c^2 - \partial_m \Pi(u \mp c)] \hat{\rho} = \\
&= \left[-c^2 - \partial_e P|_\rho \left(-\frac{h^t}{\rho} + \frac{u^2}{\rho} \right) \pm 2uc - c^2 + \frac{u}{\rho} \partial_e P|_\rho (u \mp c) \right] \hat{\rho} = \\
&= \left[-2c^2 + \partial_e P|_\rho \frac{h^t}{\rho} \pm 2uc \mp \frac{uc}{\rho} \partial_e P|_\rho \right] \hat{\rho} =
\end{aligned}$$

$$\mathbf{R} = \dots$$

$$\mathbf{L} = \dots$$

Example 20.5.3 (Shallow water equation in 1-dimensional domain)

Let $b(x) \dots, h(x)$ the height of the free surface, $\eta(x) = h(x) - b(x)$ the depth.

Derivative of integrals with non-constant extremes

$$\partial_x \int_{z=0}^{\eta(x,t)} \rho u \, dz = \int_{z=0}^{\eta(x,t)} \partial_x(\rho u) \, dz + \rho u(x, \eta(x, t), t) \partial_x \eta(x, t) .$$

Continuity equation reads

$$\partial_t \rho + \partial_x(\rho u) + \partial_z(\rho w) = 0 ,$$

for fluids with constant and uniform density

$$\begin{aligned} 0 &= \int_{z=0}^{\eta(x,t)} (\partial_t \rho + \partial_x(\rho u) + \partial_z(\rho w)) \, dz = \\ &= \partial_x \int_{z=0}^{\eta(x,t)} (\rho u) \, dz - \rho u(x, \eta, t) \partial_x \eta + \rho w(x, \eta(x, t), t) = \\ &= \partial_x \int_{z=0}^{\eta(x,t)} (\rho u) \, dz + \rho \partial_t \eta = \quad \quad \quad \simeq \partial_x(\rho \eta u) + \partial_t(\rho \eta) . \end{aligned}$$

having linked the velocity to the material derivative of the position, whose vertical component reads

$$w(x, \eta(x, t), t) = \frac{D\eta}{Dt} = \partial_t \eta(x, t) + u(x, \eta(x, t), t) \partial_x \eta .$$

Assuming hydrostatic pressure distribution, $p = P_a + \rho g z$ at depth z under the level of local free surface,

Momentum equation reads

$$0 = \partial_t(\rho u) + \partial_x(\rho u^2) + \partial_z(\rho u w) + \partial_x P .$$

and integration in z -direction **todo** Explicitly treat the z term

$$\begin{aligned} 0 &= \partial_t(\rho \eta u) + \partial_x(\rho u^2 \eta) + \partial_x \int_{z=0}^{\eta(x)} (P_a + \rho g z) \, dz = \\ &= \partial_t(\rho \eta u) + \partial_x \left(\rho u^2 \eta + \frac{1}{2} \rho g \eta^2 \right) . \end{aligned}$$

Conservative form of the equations.

$$\begin{cases} \partial_t(\eta) + \partial_x m = 0 \\ \partial_t m + \partial_x \left(\frac{m^2}{\eta} + \frac{g \eta^2}{2} \right) = 0 \end{cases}$$

Convective form of the equations.

$$\partial_t \begin{bmatrix} \eta \\ m \end{bmatrix} + \begin{bmatrix} 0 & 1 \\ -\frac{m^2}{\eta^2} + g\eta & 2\frac{m}{\eta} \end{bmatrix} \partial_x \begin{bmatrix} \eta \\ m \end{bmatrix} = \underline{0}$$

Spectrum of matrix $\mathbf{A}(\mathbf{u})$.

$$0 = |\mathbf{A}(\mathbf{u}) - s^2 \mathbf{I}| = -s(2u - s) + u^2 - g\eta = (s - u)^2 - g\eta.$$

Example 20.5.4 (P-system in n-dimensional domain)

- Conservative variables: (ρ, \vec{m})
- Physical variables: e.g. $(\rho, \vec{u}), (P, \vec{u}), \dots$

$$\begin{cases} \partial_t \rho + \nabla \cdot \vec{m} = 0 \\ \partial_t \vec{m} + \nabla \cdot \left[\frac{\vec{m} \otimes \vec{m}}{\rho} + \rho a^2 \mathbb{I} \right] = 0 \end{cases}$$

Example 20.5.5 (Euler system in n-dimensional domain)

- Conservative variables: (ρ, \vec{m}, E^t)
- Physical variables: e.g. $(\rho, \vec{u}, e), \dots$

$$\begin{cases} \partial_t \rho + \nabla \cdot \vec{m} = 0 \\ \partial_t \vec{m} + \nabla \cdot \left[\frac{\vec{m} \otimes \vec{m}}{\rho} + \Pi \mathbb{I} \right] = \vec{0} \\ \partial_t E^t + \nabla \cdot \left[\frac{\vec{m}(E^t + \Pi)}{\rho} \right] = 0 \end{cases}$$

where Π represents the pressure field as a function of the conservative variables,

$$\Pi(\rho, \vec{m}, E^t) = P(\rho, e) = P\left(\rho, \frac{E^t}{\rho} - \frac{|\vec{m}|^2}{\rho^3}\right),$$

and P the pressure field expressed by the **equation of state of the fluid** as a function of density and internal energy per unit mass as the pair of independent variables determining the thermodynamic state.

Example 20.5.6 (Shallow water equations in 2-dimensional domain)

$$\begin{cases} \partial_t(\rho\eta) + \nabla \cdot (\rho\eta\vec{u}) = 0 \\ \partial_t(\rho\eta\vec{u}) + \nabla \cdot (\rho\eta\vec{u}\vec{u} + \frac{1}{2}\rho g\eta^2 \mathbb{I}) = 0 \end{cases}$$

NAVIER-CAUCHY EQUATIONS

Navier-Cauchy equations are the differential balance equation of the momentum of an elastic isotropic medium in the regime of small strain and displacement,

$$\rho_0 \partial_{tt} \vec{s} = \rho_0 \vec{g} + \nabla \cdot \boldsymbol{\sigma}.$$

Stress tensor for an isotropic medium reads

$$\begin{aligned} \boldsymbol{\sigma} &= 2\mu \boldsymbol{\varepsilon} + \lambda \operatorname{tr}(\boldsymbol{\varepsilon}) \mathbb{I} = \\ &= \left(2\mu \boldsymbol{\varepsilon} - \frac{2}{3} \mu \operatorname{tr}(\boldsymbol{\varepsilon}) \mathbb{I} \right) + \left(\lambda + \frac{2}{3} \mu \right) \operatorname{tr}(\boldsymbol{\varepsilon}) \mathbb{I}, \end{aligned}$$

with the small strain tensor

$$\boldsymbol{\varepsilon} = \frac{1}{2} (\nabla \vec{s} + \nabla^T \vec{s}).$$

Essential, natural and Robin boundary conditions read

$$\begin{aligned} \vec{s} &= \vec{\bar{s}} & \vec{r} \in S_D & \text{essential - Dirichlet b.c.} \\ \hat{n} \cdot \boldsymbol{\sigma} &= \vec{\bar{t}}_n & \vec{r} \in S_N & \text{natural - Neumann b.c.} \\ a\vec{s} + \hat{n} \cdot \boldsymbol{\sigma} &= \vec{\bar{b}} & \vec{r} \in S_R & \text{Robin b.c.} \end{aligned}$$

21.1 Weak formulation

For $\forall \vec{w} \in \dots$

$$\begin{aligned} 0 &= - \int_V \rho \vec{w} \cdot \partial_{tt} \vec{s} + \int_V \rho_0 \vec{w} \cdot \vec{g} + \int_V \vec{w} \cdot \nabla \cdot \boldsymbol{\sigma} = \\ &= - \int_V \rho \vec{w} \cdot \partial_{tt} \vec{s} + \int_V \rho_0 \vec{w} \cdot \vec{g} + \int_{\partial V} \hat{n} \cdot \boldsymbol{\sigma} \cdot \vec{w} - \int_V \nabla \vec{w} : \boldsymbol{\sigma} \end{aligned}$$

The volume integral containing the stress tensor can be written either as

$$\begin{aligned} \int_V \nabla \vec{w} : \boldsymbol{\sigma} &= \int_V w_{i/j} [\mu (s_{i/j} + s_{j/i}) + \lambda s_{k/k} \delta_{ij}] = \\ &= \int_V \mu w_{i/j} (s_{i/j} + s_{j/i}) + \int_V \lambda w_{j/j} s_{k/k} \end{aligned}$$

or

$$\begin{aligned} \int_V \frac{1}{2} (\nabla \vec{w} + \nabla^T \vec{w}) : \boldsymbol{\sigma} &= \int_V \frac{1}{2} (w_{i/j} + w_{j/i}) [\mu (s_{i/j} + s_{j/i}) + \lambda s_{k/k} \delta_{ij}] = \\ &= \int_V \frac{\mu}{2} (w_{i/j} + w_{j/i}) (s_{i/j} + s_{j/i}) + \int_V \lambda w_{j/j} s_{k/k} \end{aligned}$$

The weak formulation of the Navier-Cauchy equations reads

$$\int_V \rho_0 \vec{w} \cdot \partial_{tt} \vec{s} + \int_V 2\mu \frac{\nabla \vec{w} + \nabla^T \vec{w}}{2} : \frac{\nabla \vec{s} + \nabla^T \vec{s}}{2} + \int_V \lambda \nabla \cdot \vec{w} \nabla \cdot \vec{s} + \int_{S_R} \vec{w} \cdot a \vec{s} = \int_V \rho_0 \vec{w} \cdot \vec{g} + \int_{S_N} \vec{w} \cdot \vec{\bar{t}}_n + \int_{S_R} \vec{w} \cdot \vec{b} ,$$

for $\forall \vec{w} \in \dots$, and with $\vec{s} = \vec{\bar{s}}$ for $\vec{r} \in S_D$.

NAVIER-STOKES EQUATIONS

Incompressible Navier-Stokes equations read

$$\begin{cases} \rho \partial_t \vec{u} + \rho (\vec{u} \cdot \nabla) \vec{u} - \mu \nabla^2 \vec{u} + \nabla P = \rho \vec{g} \\ \nabla \cdot \vec{u} = 0 . \end{cases}$$

Mass balance equation is replaced by the incompressibility kinematic constraint, $\nabla \cdot \vec{u} = 0$: this constraint is not dynamic, as time derivative of density does not appear in the equation. With the incompressibility constraint, mass equation tells us that material particles keep their density constant,

$$0 = \underbrace{\partial_t \rho + \vec{u} \cdot \nabla \rho}_{=\frac{D\rho}{Dt}} + \rho \underbrace{\nabla \cdot \vec{u}}_{=0} = \frac{D\rho}{Dt} ,$$

whose solution can be written using material coordinates \vec{r}_0 as $\rho(\vec{r}(\vec{r}_0, t), t) = \rho_0(\vec{r}_0, t)$.

22.1 Incompressibility constraint

Incompressibility constraint makes thermodynamic fade, while pressure field is replaced by/contains the contribution of a Lagrangian multiplier related to the incompressibility constraint.

22.1.1 Wave-vector transformed space

Transforming the fields from physical space to the wave-vector space $\tilde{u}(\vec{k}, t) = \mathcal{F} \{ \vec{u}(\vec{r}, t) \}$, Navier-Stokes equations for incompressible fluids with uniform and constant density $\rho(\vec{r}, t) = \rho$ becomes

$$\begin{cases} \rho \partial_t \tilde{u} + \mathcal{F} \{ (\vec{u} \cdot \nabla) \vec{u} \} + \mu |\vec{k}|^2 \tilde{u} + i \vec{k} \tilde{P} = \rho \tilde{g} \\ i \vec{k} \cdot \tilde{u} = 0 . \end{cases}$$

Taking the divergence of the momentum balance equation, i.e. taking the scalar product with $i \vec{k}$ in the transformed space, and using the incompressibility constraint to set $i \vec{k} \cdot \tilde{u} = 0$,

$$i \vec{k} \cdot \mathcal{F} \{ (\vec{u} \cdot \nabla) \vec{u} \} - |\vec{k}|^2 \tilde{P} = i \vec{k} \cdot \rho \tilde{g} ,$$

so that the transformed pressure field becomes

$$\tilde{P} = \frac{i \vec{k}}{|\vec{k}|^2} \cdot \mathcal{F} \{ (\vec{u} \cdot \nabla) \vec{u} - \rho \tilde{g} \} ,$$

Replacing this expression in the transformed Navier-Stokes equations, the meaning of the pressure field as a Lagrange multiplier associated with incompressibility constraint becomes clear,

$$\rho \partial_t \tilde{u} + \mu |\vec{k}|^2 \tilde{u} = \left[1 - \frac{\vec{k} \vec{k}}{|\vec{k}|^2} \right] \cdot \mathcal{F} \{ -(\vec{u} \cdot \nabla) \vec{u} + \rho \tilde{g} \}$$

as the orthogonal projector $[1 - \frac{\vec{k} \vec{k}}{|\vec{k}|^2}]$ onto the space of divergence-free functions acts on the non-linear and forcing terms.

22.2 Weak formulation of the problem

$$\begin{aligned}
 0 &= \int_V \vec{w} \cdot [\rho \partial_t \vec{u} + \rho(\vec{u} \cdot \nabla) \vec{u} - 2\mu \nabla \cdot \mathbb{D}(\vec{u}) + \nabla P - \rho \vec{g}] - \int_V v \nabla \cdot \vec{u} = \\
 &= \int_V \vec{w} \cdot [\rho \partial_t \vec{u} + \rho(\vec{u} \cdot \nabla) \vec{u}] + \int_V 2\mu \nabla \vec{w} : \mathbb{D} - \int_V \nabla \cdot \vec{w} P - \int_V \vec{w} \cdot \rho \vec{g} - \int_V v \nabla \cdot \vec{u} - \int_{\partial V} \hat{n} \cdot (\mathbb{S} - P \mathbb{I}) \cdot \vec{w} ,
 \end{aligned}$$

22.2.1 Weak formulation and incompressibility constraint

$$\vec{r}(\vec{r}_0, t) = \vec{r}(q(t), t)$$

$$\vec{u} = \frac{D\vec{r}}{Dt} = \dot{q} \frac{\partial \vec{r}}{\partial q} + \frac{\partial \vec{r}}{\partial t}$$

In the weak formulation, using $\vec{w} = \frac{\partial \vec{r}}{\partial q} = \frac{\partial \vec{u}}{\partial \dot{q}}$

$$\begin{aligned}
 0 &= \int_V \vec{w} \cdot \rho \frac{D\vec{u}}{Dt} + \int_V 2\mu \nabla \vec{w} : \mathbb{D} - \int_V \nabla \cdot \vec{w} P - \int_V \rho \vec{w} \cdot \vec{g} - \int_V v \nabla \cdot \vec{u} - \int_{\partial V} \vec{t}_{\hat{n}} \cdot \vec{w} , \\
 \int_V \vec{w} \cdot \rho \frac{D\vec{u}}{Dt} dV &= \int_{V_0} \rho_0 \frac{\partial \vec{u}}{\partial \dot{q}} \cdot \frac{D\vec{u}}{Dt} = \\
 &= \int_{V_0} \rho_0 \frac{D}{Dt} \left(\frac{\partial \vec{u}}{\partial \dot{q}} \cdot \vec{u} \right) dV_0 - \int_{V_0} \rho_0 \frac{D}{Dt} \left(\frac{\partial \vec{r}}{\partial \dot{q}} \right) \cdot \vec{u} dV_0 = \\
 &= \int_{V_0} \rho_0 \frac{D}{Dt} \left(\frac{\partial}{\partial \dot{q}} \frac{|\vec{u}|^2}{2} \right) dV_0 - \int_{V_0} \rho_0 \frac{\partial}{\partial q} \frac{|\vec{u}|^2}{2} dV_0 =
 \end{aligned}$$

...

22.3 Non-linear term

Different ways to treat the non-linear term:

- Semi-linear approximation of the non-linear term

$$(\vec{u}(\vec{r}, t^n) \cdot \nabla) \vec{u}(\vec{r}, t^n) \sim (\vec{u}^*(\vec{r}, t^n) \cdot \nabla) \vec{u}(\vec{r}, t^n) ,$$

with $\vec{u}^*(\vec{r}, t^n)$ an approximation of $\vec{u}(\vec{r}, t^n)$ involving values of the velocity field at previous time-steps, as an example

$$\vec{u}^*(\vec{r}, t^n) = \begin{cases} \vec{u}(\vec{r}, t^{n-1}) & 1^{st}\text{-order} \\ 2\vec{u}(\vec{r}, t^{n-1}) - \vec{u}(\vec{r}, t^{n-2}) & 2^{nd}\text{-order} \end{cases}$$

ARBITRARY LAGRANGIAN-EULERIAN DESCRIPTION

Reynold's transport theorem allows for the formulation of integral equations, and grid-based methods like FVM, on moving grids and changing domains. Rules for derivatives of composite functions provide the relations between time derivatives in a Lagrangian, Eulerian, or arbitrary description,

$$\begin{aligned}\left. \frac{\partial f}{\partial t} \right|_{\vec{r}_0} &= \left. \frac{\partial f}{\partial t} \right|_{\vec{r}} + \vec{u} \cdot \nabla f \\ \left. \frac{\partial f}{\partial t} \right|_{\vec{r}_b} &= \left. \frac{\partial f}{\partial t} \right|_{\vec{r}} + \vec{u}_b \cdot \nabla f\end{aligned}$$

Equations governing the motion of the grid are usually required as well. E.g.:

- known and prescribed motion of the grid;
- boundary conditions only without changing grids (for small displacements)
- pseudo-elastic deformation (usually good for small strain and displacement;
- for large displacements of/or models with complex geometry, sliding and/or overlapping grids could an option for grid-based methods.

23.1 Integral problem

Application of Reynolds theorem to the balance equation of the quantity \mathbf{u} for a material volume V_t

$$\frac{d}{dt} \int_{V_t} \rho \mathbf{u} = \int_{V_t} \rho \mathbf{f} + \oint_{\partial V_t} \hat{n} \cdot \mathbf{T}.$$

provides the expression of the balance equation for a geometrical volume v_t in arbitrary motion,

$$\frac{d}{dt} \int_{v_t} \rho \mathbf{u} + \oint_{\partial v_t} \rho \mathbf{u} (\vec{u} - \vec{u}_b) \cdot \hat{n} = \int_{v_t} \rho \mathbf{f} + \oint_{\partial v_t} \hat{n} \cdot \mathbf{T}.$$

Here, the integral forulation of the problem will be applied to each element of the grid in arbitrary motion, for domains with variable geometry.

23.2 Differential problem

Rules for derivatives of composite functions allows to write the differential w.r.t. the variables associated with the points of a moving grid. A balance equation in convective form can be written as

$$\begin{aligned}\rho \frac{D\mathbf{u}}{Dt} &= \rho \mathbf{f} + \nabla \cdot \mathbf{T} \\ \rho \left[\frac{\partial \mathbf{u}}{\partial t} + \vec{u} \cdot \nabla \mathbf{u} \right] &= \\ \rho \left[\frac{\partial \mathbf{u}}{\partial t} \Big|_{\vec{r}_b} + (\vec{u} - \vec{u}_b) \cdot \nabla \mathbf{u} \right] &= \end{aligned}$$

PROOF INDEX

definition-0

definition-0 (*ch/tensor-algebra-calculus/calculus-euclidean*), 25

definition-1

definition-1 (*ch/tensor-algebra-calculus/calculus-euclidean*), 25

definition-2

definition-2 (*ch/tensor-algebra-calculus/calculus-euclidean*), 25

definition-3

definition-3 (*ch/tensor-algebra-calculus/calculus-euclidean*), 26

definition-4

definition-4 (*ch/complex/analysis*), 54

definition-5

definition-5 (*ch/complex/analysis*), 55

example-0

example-0 (*ch/tensor-algebra-calculus/calculus-euclidean-spherical*), 37

example-1

example-1 (*ch/tensor-algebra-calculus/calculus-euclidean-spherical*), 37

example-10

example-10 (*ch/tensor-algebra-calculus/calculus-euclidean*), 29

example-2

example-2 (*ch/tensor-algebra-calculus/calculus-euclidean-spherical*), 37

example-3

example-3 (*ch/tensor-algebra-calculus/calculus-euclidean-spherical*), 38

example-4

example-4 (*ch/tensor-algebra-calculus/calculus-euclidean-spherical*), 38

example-5

example-5 (*ch/tensor-algebra-calculus/calculus-euclidean-spherical*), 38

example-6

example-6 (*ch/tensor-algebra-calculus/calculus-euclidean-spherical*), 38

example-7

example-7 (*ch/tensor-algebra-calculus/calculus-euclidean*), 28

example-8

example-8 (*ch/tensor-algebra-calculus/calculus-euclidean*), 28

example-9

example-9 (*ch/tensor-algebra-calculus/calculus-euclidean*), 29

matrix-stability-spectrum

matrix-stability-spectrum (*ch/ode/lti*), 83

svd-optimization-norm

svd-optimization-norm (*ch/linear-algebra/svd*), 8

theorem-0

theorem-0 (*ch/complex/fourier-transforms*), 67

theorem-6

theorem-6 (*ch/complex/analysis*), 56