Differential Equations

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Chapter 1

Introduction to Differential Equations

1.1 Definitions and Terminology

A Definition

Differential Equation An equation containing the derivatives of one or more unknown functions (or dependent variables) with respect to one or more independent variables is a **differential equation (DE)**.

Classification by Type

A differential containing only ordinary derivatives with respect to a *single* independent variables is an **ordinary differential equation (ODE)**. One involving partial derivatives is a **partial differential equation (PDE)**.

Notation

Leibniz notation denotes derivatives as ratios of differentials with the operators and variables raised to the n for the n^{th} derivative. **Prime notation** denotes the n^{th} derivative with either n primes or (n) in superscript of the dependent variable or the function. The n^{th} derivative of $y = f(x)$ can thusly be denoted as

$$\frac{\mathrm{d}^n y}{\mathrm{d}x^n} = y^{(n)} = f^{(n)}(x)$$

Newton's **dot notation** is sometimes used to denote derivatives with respect to time, placing n dots above the dependent variable to denote its n^{th} derivative with respect to t. The second derivative of x with respect to t can be denoted as

$$\ddot{x} = \frac{\mathrm{d}^2 x}{\mathrm{d}t^2}$$

Subscript Notation is often used for partial derivatives, indicating the independent variable in the subscript. The second partial x derivative with respect to z can be denoted as

$$z_{xx} = \frac{\partial^2 z}{\partial x^2}$$

Classification by Order

The **order of a differential equation** is the order of the highest derivartive in the equation.
A first-order ODE is sometimes written in the **differential form**

$$M(x, y)\,\mathrm{d}x + N(x, y)\,\mathrm{d}y = 0$$

Symbolically, an n^{th}-order ODE in one dependent variable can be expressed generally as

$$F\big(x, y, y', \ldots, y^{(n)}\big) = 0$$

where F is a real-valued function of $n+2$ variables.
It is assumed that it is possible to solve an ODE in the form above uniquely for the highest derivative $y^(n)$ in terms of the remaining $n+1$ variables.
The **normal form** of the above expression is

$$\frac{\mathrm{d}^n y}{\mathrm{d}x^n} = f\big(x, y, y', \ldots, y^{(n-1)}\big)$$

where f is a real-values continuous function.
The following normal forms can be used to represent general first- and second-order ODEs:

$$\frac{\mathrm{d}y}{\mathrm{d}x} = f(x, y) \qquad\qquad \frac{\mathrm{d}^2 y}{\mathrm{d}x^2} = f(x, y, y')$$

Classification by Linearity

An general n^{th} order ODE is **linear** if F is linear in $y, y', y^{(n)}$. This means that it is linear when

$$a_n(x)\frac{\mathrm{d}^n y}{\mathrm{d}x^n} + a_{n-1}(x)\frac{\mathrm{d}^{n-1} y}{\mathrm{d}x^{n-1}} + \cdots + a_1(x)\frac{\mathrm{d}y}{\mathrm{d}x} + a_0(x)y = g(x)$$

Two important special cases of the above are linear first-[1] and second-order DEs:

$$a_1(x)\frac{\mathrm{d}y}{\mathrm{d}x} + a_0(x)y = g(x) \qquad\qquad a_2(x)\frac{\mathrm{d}^2 y}{\mathrm{d}x^2} + a_1(x)\frac{\mathrm{d}y}{\mathrm{d}x} + a_0(x)y = g(x)$$

The characteristic properties of linear ODEs are that the dependent variable and all of its derivatives are of first degree and that the coefficients of those terms are dependent at most on the independent variable.
A **nonlinear** ODE is one that is not linear.
Nonlinear functions of the dependent variable cannot appear in linear ODEs.
A DE can not be classified as linear or nonlinear if both differentials are in the numerator.

Solutions

Solution of an ODE Any function φ defined on an interval I with at least n derivatives that are continuous on I which when substituted into an n^{th}-order ODE reduce the equation to an identity is a **solution** of the equation on the interval.

[1] A first order ODE written in differential form as $M(x, y)\,\mathrm{d}x + N(x, y)\,\mathrm{d}y = 0$ may be linear or nonlinear, as there is no indication of which symbol is the dependent variable.

A DE need not have a solutions. A solution of a DE may involve **integral-defined function**[2].
A solution of a general n^{th}-order ODE is a function φ with at least n derivatives for which

$$F\big(x, \varphi(x), \varphi'(x), \ldots, \varphi^{(n)}(x)\big) = 0 \qquad \forall\, x \in I$$

φ is said to *satisfy* the differential equation on I. It is assumed that a solution φ is a real-valued function.
A solution is occasionally denoted alternatively by $y(x)$.

Interval of Definition

The interval I over which φ satisfies the ODE is referred to as the **interval of definition/existence/validity** or the **domain of the solution**.
A solution of a DE that is identically 0 on an interval I is said to be a **trivial solution**.

Solution Curve

The graph of φ is called a **solution curve**.
The domain of φ need not be the same as I.

Explicit and Implicit Solutions

A function that expresses the dependent variable solely in terms of the independent variable and constants is said to be *explicit*. An **explicit solution** is a solution with an explicit function. It can be thought of as an explicit formula $y = \varphi(x)$ that can be manipulated.
An explicit solution is generally not needed over an implicit one.
An implicit solution $G(x, y) = 0$ may define a differentiable function that is a solution of a DE despite $G(x, y) = 0$ potentially not being solvable analytically. The solution curve may be a segment of the graph of $G(x, y) = 0$.

Families of Solutions

When solving a first-order DE, the solution *usually* contains a single constant or parameter C, similar to the constant of integration obtained from the indefinite integral. A solution of $F(x, y, y') = 0$ containing constant C is a set of solutions $G(x, y, C) = 0$ called a **one-parameter family of solutions**.

[2] A function F of a single variable x can be defined as

$$F(x) = \int_a^x g(t)\,\mathrm{d}t$$

If the integrand g is continuous over $[a, b]$ and x falls within the interval, then F is differentiable on the open interval and

$$F'(x) = \frac{\mathrm{d}}{\mathrm{d}x} \int_a^x g(t)\,\mathrm{d}t = g(x)$$

The integral is often **nonelementary**, meaning that it is not composed of elementary functions.
Elementary functions include constant, polynomial, rational, exponential, logarithmic, trigonometric, and inverse trigonometric functions, as well as rational powers and finite combinations using the four basic arithmetic operations and compositions of these functions.

An n^{th}-order DE[3] often yields an **n-parameter family of solutions**[4] $G(x, y, C_1, C_2, \dots, C_n) = 0$. The parameters in a family of solutions are *arbitrary* up to a point, but they should always take on values that make sense in the real-number system.
A **singular solution** is one that cannot be obtained by specializing *any* of the parameters in the family of solutions.

Systems of Differential Equations

A **system of ODEs** is comprised of multiple unknown functions of a single independent variable.
A **solution** of a system is a pair of differentiable functions defined on common interval I that satisfy each equation of the system on the interval.

1.2 Initial-Value Problems

Often, a solution to a DE must meet other conditions imposed on it and its derivatives.

$$\frac{\mathrm{d}^n y}{\mathrm{d}x^n} = f\big(x, y, y', \dots, y^{(n-1)}\big) \mid y(x_0) = y_0, y'(x) = y_1, \dots, y^{(n-1)}(x_0) = y_{n-1}$$

If these desired values are constants, this is an **n^{th}-order initial-value problem (IVP)**. The desired values are called **initial conditions (IC)**.[5]
Solving an n^{th}-order IVP often requires that an n-parameter family of solutions be found that can then be used in tandem with the constraints to find the constants. The resulting particular solution is defined on some interval that contains x_0.

Geometric Interpretation

A first-order IVP

$$\frac{\mathrm{d}y}{\mathrm{d}x} = f(x, y) \mid y(x_0) = y_0$$

can be interpreted as finding a solution $y(x)$ with a graph that passes through the point (x_0, y_0).
A second-order IVP

$$\frac{\mathrm{d}^2 y}{\mathrm{d}x^2} = f(x, y, y') \mid y(x_0) = y_0, y'(x_0) = y_1$$

can be interpreted as finding a solution $y(x)$ with a graph that passes through (x_0, y_0) with slope y_1.

---

[3] $F\big(x, y, y', \dots, y^{(n)}\big) = 0$ may not always be solvable for $y^{(n)}$.

[4] If *every* solution of an n^{th}-order ODE on an interval can be found by manipulating the parameters of an n-parameter family of solutions, then the family is said to be the **general solution** of the DE.
Nonlinear ODEs are often difficult of impossible to solve in terms of elementary functions, so if a family of solutions is found for one, it is unclear whether it is a general solution. Practically, the designation of "general solution" is only given for solutions to linear ODEs.

[5] If conditions are prescribed at multiple points, called **boundary conditions**, the problem is called a **boundary-value problem (BVP)**.

Existence and Uniqueness

It can be assumed that *most* DEs will hav solutions and that the solutions of IVPs will *generally* be unique.

Theorem 1.2.1 Let R be a rectangular region in the xy-plane defined by

$$R = \{(x, y) \mid a \leq x \leq b, c \leq y \leq d\}$$

that contains point (x_0, y_0). If $f(x, y)$ and $\partial f/\partial y$ are continuous over R[a], then there exists some interval $I_0 : (x_0 - h, x_0 + h)$ (where $h > 0$) contained in $[a, b]$ and a unique function $y(x)$ defined on this interval that is a solution of the IVP.

[a] These conditions are sufficient but not necessary. When $f(x, y)$ and $\partial f/\partial y$ are continuous on R, a solution of the IVP exists and is unique so long as (x_0, y_0) is contained within R. If these conditions are not met, though, the IVP *may* still have a solution that *may* be unique, or it may have multiple or no solutions.

Interval of Existence/Uniqueness

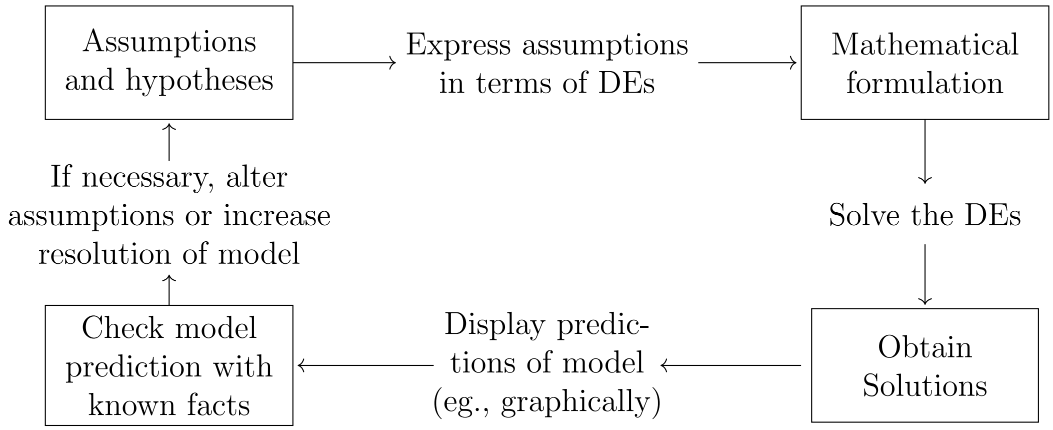
The domain of the function that represents a solution to an IVP, the interval I over which the solution is defined or exists, and the interval I_0 of existence *and* uniqueness.
Suppose (x_0, y_0) is a point in the interior of rectangle R. The continuity of function $f(x, y)$ on R is sufficient to guarantee the existence of at least on solution of $\mathrm{d}y/\mathrm{d}x = f(x, y)$, $y(x_0) = y_0$), defined on some interval I. The interval of definition I for this IVP is generally taken to be the largest interval containing x_0 over which the solution $y(x)$ is both defined and differentiable. The interval depends both on the DE and the initial condition.
The condition of continuity of $\partial f/\partial y$ on R means that the solution on I_0 containing x_0 is the *only* solution satisfying the initial condition.
It should be noted that the interval of definition I may not be as wide as R and the interval of existence I_0 and uniqueness may not be as large as I. The number $h > 0$ that defines I_0 may be very small, so the solution $y(x)$ should bed thought of as *unique locally*: a solution defined near (x_0, y_0).

1.3 Differential Equations as Mathematical Models

Mathematical Models

A **mathematical model** is a mathematical description of some system or phenomenon.
To construct a mathematical model, one must first identify the independent variables of the system. The model's **level of resolution** is determined by which variables are chosen to be included From there, a set of hypotheses about the system can be made. These will include any empirical laws that may apply.
Assumptions made regarding a system often involve *rates of change*, so their models often include *derivatives*; that is to say, mathematical models often take the form of DEs or system of them.
If the DE or system is solvable, then the model can be considered reasonable if the solution is in line with data or known facts. Otherwise, the level of resolution can be increased or alternative assumptions can be made.

Steps in the modeling process with differential equations



Increasing the resolution also increases the complexity of the model, meaning that an explicit solution becomes less likely.
Mathematical models of physical systems often involve time as a variable t. A solution gives the **state of the system**.

Population Dynamics

The **Malthusian model for population growth** assumes that the the growth rate over a certain time is proportional to the total population at that time.

$$\frac{\mathrm{d}P}{\mathrm{d}t} \propto P \qquad \text{or} \qquad \frac{\mathrm{d}P}{\mathrm{d}t} = kP$$

Due to its simplicity, it is only used to model the *growth of small populations over short intervals*. This model is also used for the model of continuous compound interest $\mathrm{d}S/\mathrm{d}t = rS$ (where S is capital and r is the annual interest rate).

Radioactive Decay

Radioactive decay can be modeled under the assumption that the rate $\mathrm{d}A/\mathrm{d}t$ at which a substance's nuclei decay is proportional to the number of nuclei $A(t)$ of the substance remaining at time t.

$$\frac{\mathrm{d}A}{\mathrm{d}t} \propto A \qquad \text{or} \qquad \frac{\mathrm{d}A}{\mathrm{d}t} = kA$$

This model is also used to determine a drug's half-life and in the model of a first-order chemical reaction.

A single differential equation may serve as a mathematical model for many phenomena.

Mathematical models often have side conditions, meaning that they may either be IVPs or BVPs.

Newton's Law of Warming/Cooling

Newton's law of cooling/warming can be expressed as

$$\frac{\mathrm{d}T}{\mathrm{d}t} \propto T - T_m \qquad \text{or} \qquad \frac{\mathrm{d}T}{\mathrm{d}t} = k(T - T_m)$$

where T is temperature of the body, T_m is the temperature of the surrounding medium, and t is time.

Spread of a Disease

The spread of a disease can be modeled as

$$\frac{\mathrm{d}x}{\mathrm{d}t} = kxy$$

where $x(t)$ is the number of people that have contracted the disease and $y(t)$ is the number of people that have not been exposed. The product of these two can be used to approximate the number of interactions between the two groups.

Chemical Reactions

Radioactive decay is a **first-order reaction**. Such a reaction can be modeled as

$$\frac{\mathrm{d}X}{\mathrm{d}t} = kX$$

where $X(t)$ is the amount of substance A remaining.
Suppose one molecule each of substances A and B is used to form a single molecule of substance C. If X is the amount of C formed and α and β are the initial amounts of A and B, then the instantaneous amounts of A and B that have not yet been converted are $\alpha - X$ and $\beta - X$ respectively. The rate of formation of C is therefore given by

$$\frac{\mathrm{d}X}{\mathrm{d}t} = k(\alpha - X)(\beta - X)$$

A reaction modeled by this is said to be a **second-order reaction**

Mixtures

If $A(t)$ denotes the amount of salt at time t, then the rate at which this changes is

$$\frac{\mathrm{d}A}{\mathrm{d}t} = R_{\text{in}} - R_{\text{out}}$$

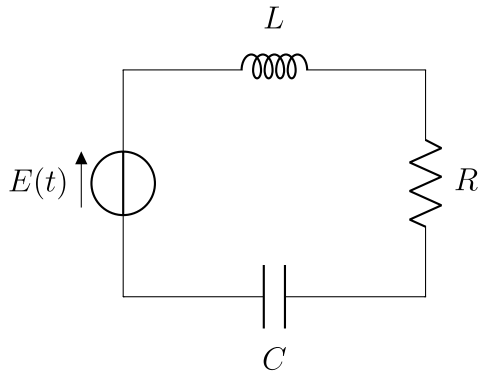
Draining a Tank

Torricelli's law states that the speed v of efflux of water through a sharp-edged hole at the bottom of a container filled to depth h is equal to the speed that a body would acquire in free fall from the same height ($v = \sqrt{2gh}$ where g is acceleration due to gravity). If the are of the hole is A_h and the speed of water leaving is $v = \sqrt{2gh}$, then the volume of water leaving per second is $A_h\sqrt{2gh}$. If $V(t)$ denotes the volume of water remaining at time t, then

$$\frac{\mathrm{d}V}{\mathrm{d}t} = -A_h\sqrt{2gh}$$

Series Circuits

Consider the single-loop LRC-series circuit



containing an inductor, a resistor, and a capacitor. The current remaining in a circuit after a switch is closed is denoted by $i(t)$ while the charge on a capacitor is denoted by $q(t)$. L, R, and C denote inductance, resistance, and capacitance respectively and are generally constants.
According to **Kirchhoff's second law**, the impressed voltage $E(t)$ on a closed loop must be equal to the sum of the voltage drops in the loop. As current $i(t)$ is related to charge $q(t)$ by $i = \mathrm{d}q/\mathrm{d}t$, equating the sum of the 3 voltages

$$L\frac{\mathrm{d}i}{\mathrm{d}t} = L\frac{\mathrm{d}^2q}{\mathrm{d}t^2} \qquad iR = R\frac{\mathrm{d}q}{\mathrm{d}t} \qquad \frac{1}{C}q$$

to the impressed voltage yields a second-order DE

$$L\frac{\mathrm{d}^2q}{\mathrm{d}t^2} + R\frac{\mathrm{d}q}{\mathrm{d}t} + \frac{1}{C}q = E(t)$$

Falling Bodies

Newton's first law of motion states that a body in motion will stay in motion and one at rest will stay at rest unless acted upon by an external force. Both statements are equivalent to stating that the sum of the forces (the *net*/resultant force) acting on the body is 0, then so is its acceleration.
Newton's second law of motion states that $F = ma$, where F is force, m is mass, and a is acceleration.

Falling Bodies and Air Resistance

A falling body of mass m may encounter air resistance proportion to its velocity v. The net force acting on such a mass is given by $F = mg - kv$, (k being a positive constant of proportionality) the former term being the force of gravity and the latter being that of air resistance, called **viscous damping**. As $a = \mathrm{d}v/\mathrm{d}t$, Newton's second law can be rewritten a

$$F = ma = m\frac{\mathrm{d}v}{\mathrm{d}t}$$

Equating the net force to this form of Newton's second law yields a first-order DE for the velocity $v(t)$:

$$m\frac{\mathrm{d}v}{\mathrm{d}t} = mg - kv$$

In terms of position s,

$$m\frac{\mathrm{d}^2 s}{\mathrm{d}t^2} = mg - k\frac{\mathrm{d}s}{\mathrm{d}t}$$

Suspended Cables

Suppose a flexible cable is suspended between two vertical supports. Let P_1 denote its lowers hanging point and P_2 some arbitrary point. The portion of the cable connecting these two points is a curve in the xy-plane, the y-axis passing through P_1 and the x-axis being a units below P_1. There are 3 forces acting on the cable: the tensions $\vec{T}_1$ and $\vec{T}_2$ tangent to the cable at P_1 and P_2 respectively and the weight of the cable $\vec{W}$. Let $T_1 = |\vec{T}_1|$, $T_2 = |\vec{T}_2|$, and $W = |\vec{W}|$. The tension $\vec{T}_2$ is the only force with both vertical and horizontal components. As the system, is in static equilibrium,

$$T_1 = T_2 \cos\theta \qquad\qquad W = T_2 \sin\theta$$

Dividing the former equation by the latter, T_2,

$$\tan\theta = \frac{W}{T_1}$$

As $\mathrm{d}y/\mathrm{d}x = \tan\theta$,

$$\mathrm{d}y/\mathrm{d}x = \frac{W}{T_1}$$

Chapter 2

First-Order Differential Equations

2.1 Solution Curves without a Solution

If a DE is not explicitly or analytically solvable, it still provides information regarding its solution curve.

2.1.1 Direction Fields

Slope

As the solution $y = y(x)$ of the first order DE

$$\frac{\mathrm{d}y}{\mathrm{d}x} = f(x, y)$$

must be differentiable on its interval of definition I, it must also be continuous on said interval. The function f in normal form, as presented above, is called the **slope/rate function**. The slope of the tangent line at point $(x, y(x)$ is equal to $f(x, y(x))$.
Let (x, y) represent any point in the xy-plane for which f is defined. The value of the function at that point represents the slope of a line segment called a **lineal element**, which is some segment of the tangent line at that point.

Direction Field

A **direction/slope field** is a plot of small lineal elements over some region in the xy-plane. Visually, it provides information regarding the shape of a family of solution curves, allowing qualitative aspects of said family to be discerned. A solution curve passing through the field must follow the flow of the grid, being tangent to the lineal element at any point it intersects one.

Increasing/Decreasing

The sign of the first derivative provides information regarding whether the function is increasing or decreasing.

$\mathrm{d}y/\mathrm{d}x$	< 0	> 0
function behavior	decreasing	increasing

2.1.2 Autonomous First-Order DEs

Autonomous First-Order DEs

An ODE that does not explicitly contain the independent variable is said to be **autonomous**. If x is independent and y is dependent, an autonomous DE would take the form

$$f(y, y') = 0 \qquad \text{or} \qquad \frac{\mathrm{d}y}{\mathrm{d}x} = f(y)$$

It is assumed that f isa continuous and differentiable function of y on some interval I.

Critical Points

A real number c is a **critical/equilibrium/stationary point** of an autonomous DE if $f(c) = 0$. If the constant function $y(x) = c$ is substituted into the normal form of an autonomous de, both sides equate to 0.

$$\boxed{\textit{If } c \textit{ is a critical point of an autonomous DE, then } y(x) = c \textit{ is a constant solution.}}$$

A constant solution $y(x) = c$ is also referred to as an **equilibrium solution**, equilibria being the *only* constant solutions. A **(one dimensional) phase portrait** consists of a vertical **phase line** (the P-axis) displaying the intervals on which a function is increasing or decreasing between equilibria.

Solution Curves

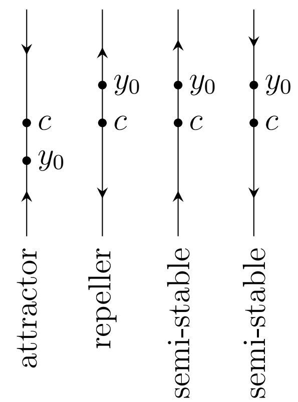
As f is independent of x, it may be considered defined for $-\infty < x < \infty$ or $0 \leq x < \infty$. As f is continuous and differentiable for y on some interval I of the y-axis, some horizontal region R can be formed in the xy-plane using I. Through any point x_0, y_0 in R passes only a single solution curve. Suppose R is split into subregions R_i by equilibria $y(x) = c_i$.

- If a solution curve passes through point x_i, y_i in R_i, it must stay within R_i for all x, as the curve is continuous and cannot cross equilibria.
- As f is continuous over R, $f(y)$ must be either entirely positive or entirely negative for all x in R_i.
- As $\mathrm{d}y/\mathrm{d}x = f(y(x))$, all solution curves must be monotonic.
- If $y(x)$ is *bounded* by 1 or 2 critical points, then the graph must asymptotically approach them.

Attractors and Repellers

A critical point c may be an **attractor** of $y(x)$, an initial point sufficiently close resulting in $\lim\limits_{x \to \infty} y(x) = c$, a **repeller**, an initial point sufficiently close resulting in movement away from c, or neither, attracting on one side and repelling on the other. Respectively, these are referred to as

asymptotically stable, **unstable**, and **semi-stable**.



Autonomous DEs and Direction Fields

As $\mathrm{d}y/\mathrm{d}x$ is solely dependent on y, the slopes of the lineal elements displayed in a direction field will depend solely on the points' y-coordinates.
Lineal elements that pass through the same *horizontal* line have the same slopes while those that pass through the same *vertical* line may vary.

Translation Property

If $y(x)$ is a solution to an autonomous DE, then $y_1(x) = y(x-k)$ where k is a constant is as well.

This is due to the fact that an autonomous DE is not dependent on x while the solution curve is.

2.2 Separable Equations

The simplest of all DEs fall under the category of first-order separable ODEs.

Solution by Integration

When $\mathrm{d}y/\mathrm{d}x$ is solely dependent on x ($f(x,y) = g(x)$, integration can be used to solve the DE. If both sides are continuous,

$$y = \int g(x)\,\mathrm{d}x = G(x) + C$$

A Definition

Separable Equation A first-order DE of the form

$$\frac{\mathrm{d}y}{\mathrm{d}x} = g(x)h(y)$$

is said to be **separable**, having **separable variables**.

From this form, it can be seen that

$$p(y)\frac{\mathrm{d}y}{\mathrm{d}x} = g(x)$$

where $p(y) = 1/h(y)$. The derivative can then be split so that both differentials are in the numerator.

$$\int p(y)\,\mathrm{d}y = \int g(x)\,\mathrm{d}x$$

Integrating,

$$P(y) = G(x) + C$$

Method of Solution

A on-parameter family of solutions can be obtained by integrating.[1]

Losing a Solution

It should be noted that variable divisors may be zero at a point. Constant solutions are often lost through division.

Use of Computers

A computer algebra system (CAS) can be used to produce level curves defined by equating the implicit solution $G(x, y)$ to various values of c.
It should be noted that an IVP may have nontrivial solutions that are part of the same family. In fact, all member of a family may be solutions.

An Integral-Defined Function

The solution of an IVP $\mathrm{d}y/\mathrm{d}x = g(x)$, $y(x_0) = y_0$ defined on interval I containing x_0 and x over which g is continuous is given by

$$y(x) = y_0 + \int_{x_0}^{x} g(t)\,\mathrm{d}t$$

When the integral is nonelementary, this is acceptable as a final solution.

2.3 Linear Equations

A Definition

Definition 2.3.1. Linear Equation A first-order DE of the form

$$a_1(x)\frac{\mathrm{d}y}{\mathrm{d}x} + a_0(x)y = g(x)$$

is a **linear equation** in y.[a]

[a] A first-order DE may occasionally be linear in one variable but not the other.

[1] It should be noted that there is no need for multiple constants of integration for a separable equation, as their difference can simply be replaced by a single constant.

Standard Form

By dividing by $a_1(x)$, the **standard form** of a first-order linear equation is obtained:

$$\frac{\mathrm{d}y}{\mathrm{d}x} + P(x)y = f(x)$$

A solution of this should be on an interval I over which both P and f are continuous.

Method of Solution

The left hand side of the standard form of a first-order linear DE can be rewritten as the derivative of a product by multiplying by $\mu(x)$.

$$\frac{\mathrm{d}}{\mathrm{d}x}[\mu(x)] = \mu\frac{\mathrm{d}y}{\mathrm{d}x} + \frac{\mathrm{d}\mu}{\mathrm{d}x}y = \mu\frac{\mathrm{d}y}{\mathrm{d}x} + \mu P y$$

Evidently,

$$\frac{\mathrm{d}\mu}{\mathrm{d}x} = \mu P \implies \frac{\mathrm{d}\mu}{\mu} = P\,\mathrm{d}x \implies \ln|\mu| = \int P(x)\,\mathrm{d}x \implies \mu = \mathrm{e}^{\int P(x)\mathrm{d}x}$$

The constant of integration is chosen to be 1 for simplicity. This result is called the **integrating factor**. Substituting in,

$$\frac{\mathrm{d}}{\mathrm{d}x}\left[y\,\mathrm{e}^{\int P(x)\mathrm{d}x}\right] = \int P(x)\,\mathrm{d}x\frac{\mathrm{d}y}{\mathrm{d}x} + P(x)\,\mathrm{e}^{\int P(x)\mathrm{d}x}\,y = \mathrm{e}^{\int P(x)\mathrm{d}x}\,f(x)$$

Integrating both sides,

$$y\,\mathrm{e}^{\int P(x)\mathrm{d}x} = \int \mathrm{e}^{\int P(x)\mathrm{d}x}\,f(x)\,\mathrm{d}x$$

Solving for y produces a one-parameter family of solutions

$$y = \mathrm{e}^{-\int P(x)\mathrm{d}x}\left(\int \mathrm{e}^{\int P(x)\mathrm{d}x}\,f(x)\,\mathrm{d}x + C\right)$$

Solving a First-Order Linear DE

1. Put the equation into standard form.
2. Identify $P(x)$ to find the integrating factor $\mathrm{e}^{\int P(x)\mathrm{d}x}$. Evaluate the integral, forgoing the integration constant.
3. Multiply both sides by the integrating factor:

$$\frac{\mathrm{d}y}{\mathrm{d}x}\left[y\,\mathrm{e}^{\int P(x)\mathrm{d}x}\right] = \mathrm{e}^{\int P(x)\mathrm{d}x}\,f(x)$$

4. Integrate both sides and solve for y.

General Solutions

Suppose P and f, found in the standard form of a first-order linear DE, are continuous on I. *If* a solution of the DE exists on I, it must be of the form found via the integrating factor. Conversely, any function in this form is a solution on I. In other words, the family of solutions found via the integrating factor contains *every* solution defined on I. This family is therefore referred to as the **general solution** on I.
A **transient term** in a solution os one that becomes negligible for increasing values of the dependent variable.

Piecewise-Linear Differential Equation

When $P(x)$ or $f(x)$ are piecewise functions, the equation is referred to as a **piecewise-linear differential equation**.

Error Function

Many important functions are defined in terms of nonelementary integrals. Two such functions are the **error** and **complementary error functions**, denoted erf and erfc respectively and defined as

$$\operatorname{erf}(x) = \frac{2}{\sqrt{\pi}} \int_0^x \mathrm{e}^{-t^2}\,\mathrm{d}t \qquad \operatorname{erfc}(x) = \frac{2}{\sqrt{\pi}} \int_x^\infty \mathrm{e}^{-t^2}\,\mathrm{d}t$$

It is known that the definite integral from 0 to ∞ of e^{-t^2} is equal to $\sqrt{2\pi}/2$, so

$$\frac{2}{\sqrt{\pi}} \int_0^\infty \mathrm{e}^{-t^2}\,\mathrm{d}t = 1$$

Using the additive property of definite integrals, this can be rewritten as

$$\frac{2}{\sqrt{2\pi}} \int_0^\infty \mathrm{e}^{-t^2}\,\mathrm{d}t = \frac{2}{\sqrt{\pi}} \int_0^x \mathrm{e}^{-t^2}\,\mathrm{d}t + \frac{2}{\sqrt{\pi}} \int_x^\infty \mathrm{e}^{-t^2}\,\mathrm{d}t = 1$$

It is then apparent why that

$$\operatorname{erf}(x) + \operatorname{erfc}(x) = 1$$

When the solution of an IVP involves a nonelementary integral, it is often beneficial to use a *definite* integral from x_0 to x.

2.4 Exact Equations

Differential of a Function of Two Variables

Recall that for a function $z = f(x, y)$ with continuous partial derivatives in region R, its **differential** is defined as

$$\mathrm{d}z = \frac{\partial f}{\partial x}\,\mathrm{d}x + \frac{\partial f}{\partial y}\,\mathrm{d}y$$

If z is constant,

$$\frac{\partial f}{\partial x}\,\mathrm{d}x + \frac{\partial f}{\partial y}\,\mathrm{d}y = 0$$

So given a one parameter family of solutions $f(x, y) = c$, f first-order DE can be generated by computing the differential of both sides of the equality.

A Definition

Exact Equation A differential expression $M(x, y)\,\mathrm{d}x + N(x, y)\,\mathrm{d}y$ is an **exact differential** in region R of the xy-plane if it corresponds to the differential of some function $f(x, y)$ on R. A first-order DE of the form

$$M(x, y)\,\mathrm{d}x + N(x, y)\,\mathrm{d}y = 0$$

is said to be an **exact equation** if the expression on the left is an exact differential.

Theorem 2.4.1 Criterion for an Exact Differential If $M(x, y)$ and $N(x, y)$ are continuous and first-differentiable in a rectangular region R, then $M(x, y)\,\mathrm{d}x + N(x, y)\,\mathrm{d}y$ is said to be an exact differential if and only if

$$\frac{\partial M}{\partial y} = \frac{\partial N}{\partial x}$$

Method of Solution

If the differential is exact, there exists a function f for which

$$\frac{\partial f}{\partial x} = M(x, y) \qquad \text{and} \qquad \frac{\partial f}{\partial y} = N(x, y)$$

Integration and partial differentiation can be used to find this function.

$$f(x, y) = \int M(x, y)\,\mathrm{d}x + g(y)$$

$$\frac{\partial f}{\partial y} = N(x, y) = \frac{\partial}{\partial y} \int M(x, y)\,\mathrm{d}x + g'(y)$$

2.5 Solutions by Substitutions

Substitutions

Solving a DE often involves first transforming it into another DE via **substitution**.
To transform the first-order DE $\mathrm{d}y/\mathrm{d}x = f(x, y)$ using the substitution $y = g(x, u)$, where u is regarded as a function of x, the chain rule can be used (so long as g has first-partial derivatives)

$$\frac{\mathrm{d}y}{\mathrm{d}x} = \frac{\partial g}{\partial x}\frac{\mathrm{d}x}{\mathrm{d}y} + \frac{\partial g}{\partial u}\frac{\mathrm{d}u}{\mathrm{d}x}$$

gives

$$\frac{\mathrm{d}y}{\mathrm{d}x} = g_x(x, u) + g_u(x, u)\frac{\mathrm{d}u}{\mathrm{d}x}$$

The DE then becomes

$$g_x(x, u) + g_u(x, u)\frac{\mathrm{d}u}{\mathrm{d}x} = f(x, g(x, u))$$

Solving for $\mathrm{d}u/\mathrm{d}x$ yields the form

$$\frac{\mathrm{d}u}{\mathrm{d}x} = F(x, u)$$

If a solution $u = \varphi(x)$ can be found, then a solution of the original DE is

$$y = g(x, \varphi(x))$$

Homogenous Equations

A function f is said to be a **homogenous function** of degree α if $f(tx, ty) = t^\alpha f(x, y)$ for some real number α.
A first-order DE in differential form

$$M(x, y)\,\mathrm{d}x + N(x, y)\,\mathrm{d}y = 0$$

is **homogenous** if both M and N are homogenous functions of the *same* degree; that is, if

$$M(tx, ty) = t^\alpha M(x, y) \qquad \text{and} \qquad N(tx, ty) = t^\alpha N(x, y)$$

If this is true, it can also be written that

$$M(x, y) = x^\alpha M(1, u) \qquad \text{and} \qquad N(x, y) = x^\alpha N(1, u) \qquad \text{where } u = \frac{y}{x}$$

and

$$M(x, y) = y^\alpha M(v, 1) \qquad \text{and} \qquad N(x, y) = y^\alpha N(v, 1) \qquad \text{where } v = \frac{x}{y}$$

Either $y = ux$ or $x = vy$ can be used to reduce a homogenous DE to a *separable* first-order De.

Bernoulli's Equation

The DE

$$\frac{\mathrm{d}y}{\mathrm{d}x} + P(x)y = f(x)y^n$$

where n is any real number is called **Bernoulli's equation**. For $n \neq 0, 1$, the substitution $u = y^{1-n}$ can be used.

Reduction to Separation of Variables

A DE of the form

$$\frac{\mathrm{d}y}{\mathrm{d}x} = f(Ax + By + C)$$

can always be reduced to a separable equation by the substitution $Ax + By + C$ so long as $B \neq 0$.

Chapter 3

Modeling with First-Order Differential Equations

3.1 Linear Models

Growth and Decay

The IVP

$$\frac{\mathrm{d}x}{\mathrm{d}t} \propto x, \quad x(t_0) = x_0$$

can model growth or decay.

Half-Life

A substance's **half-life** is the amount of time that it takes for half of the atoms in the initial amount A_0 to disintegrate or transmute into those of another element. The longer a substance's half-life, the more stable it is.

Newton's Law of Cooling/Warming

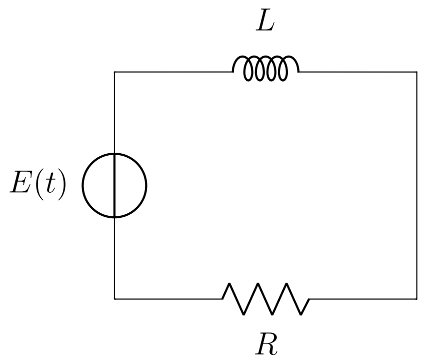
Newton's law of cooling/warming is given by

$$\frac{\mathrm{d}T}{\mathrm{d}t} = k(T - T_m)$$

where $T(t)$ is the temperature of the object, T_m is the ambient temperature, and k is a proportionality constant.

Series Circuits

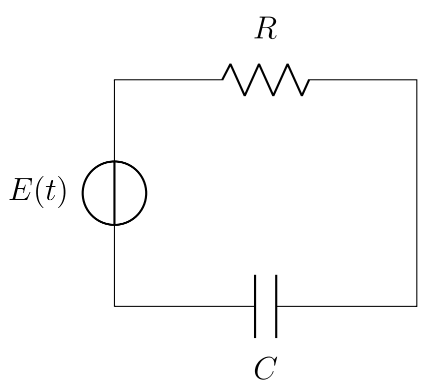
For an LR-series circuit



containing only a resistor and an inductor, Kirchhoff's second law states that the sum of the voltage drop across the inductor ($L(\mathrm{d}i/\mathrm{d}t)$) and that across the resistor (iR) is equal to the impressed voltage ($E(t)$) on the circuit. This provides the first-order linear DE

$$L\frac{\mathrm{d}i}{\mathrm{d}t} + Ri = E(t)$$

for the current $i(t)$, where L and R are the inductance and resistance respectively. The current is also called the **response** os the system.
The voltage drop across a capacitor with capacitance C is given by $q(t)/C$, q being the charge on the capacitor. For an RC-series circuit



Kirchhoff's second law then gives

$$Ri + \frac{1}{C}q = E(t)$$

As i and q are related by $i = \mathrm{d}q/\mathrm{d}t$, though, this can be rewritten as the linear DE

$$R\frac{\mathrm{d}q}{\mathrm{d}t} + \frac{1}{c}q = E(t)$$

3.2 Nonlinear Models

Population Dynamics

If $P(t)$ denotes a population's size at time t, the model for exponential growth begins by assuming that $\mathrm{d}P/\mathrm{d}t + kP$ for some $k > 0$. In this model, the **relative/specific growth rate**, as defined by

$$\frac{\mathrm{d}P/\mathrm{d}t}{P}$$

is a constant k.

As resources are finite, true exponential growth over long periods of time is essentially unheard of. The assumption that a population's growth is dependent only on the size of the population can be states as

$$\frac{\mathrm{d}P/\mathrm{d}Pt}{P} = f(P) \qquad \text{or} \qquad \frac{\mathrm{d}P}{\mathrm{d}t} = Pf(P)$$

This DE is called the **density-dependent hypothesis**.

Logistic Equation

Suppose that the maximum number of individuals sustainable in a population is K. This quantity K is called the environment's **carrying capacity**. For the DE, then,

$$f(K) = 0 \qquad \text{and} \qquad f(0) = r$$

The simplest assumption to satisfy these conditions is that $f(P)$ is linear:

$$f(P) = c_1 P + c_2$$

Using the conditions, we find that $c_2 = r$ and $c_1 = -r/K$, so

$$f(P) = r - \frac{r}{K}P$$

The DE then becomes

$$\frac{\mathrm{d}P}{\mathrm{d}t} = P\left(r - \frac{r}{K}P\right)$$

Relabeling the constants,

$$\frac{\mathrm{d}P}{\mathrm{d}t} = P(a - bP)$$

Solution of the Logistic Equation

The logistic model can be solved via separation of variables:

$$a$$

$$\begin{aligned}
\left(\frac{1/a}{P} + \frac{b/a}{a - bP}\right)\mathrm{d}P &= \mathrm{d}t \\
\frac{1}{a}\ln|P| - \frac{1}{a}\ln|a - bP| &= t + c \\
\ln\left|\frac{P}{a - bP}\right| &= at + ac \\
\frac{P}{a - bP} &= c_1\,\mathrm{e}^{at}
\end{aligned}$$

It then follows that

$$P(t) = \frac{ac_1\,\mathrm{e}^{at}}{1 + bc_1\,\mathrm{e}^{at}} = \frac{ac_1}{bc_1 + \mathrm{e}^{-at}}$$

If $P(0) = P_0 \neq a/b$, then $c_1 = P_0/(a - bP_0)$, so

$$P(t) = \frac{aP_0}{bP_0 + (a - bP_0)\,\mathrm{e}^{-at}}$$

Chemical Reactions

Suppose a grams of chemical A and b grams of chemical B are combined. If there are M parts of A and N parts of B formed in the compound, then the number of grams of chemicals A and B remaining at time t are respectively

$$a - \frac{M}{M+N}X \qquad \text{and} \qquad b - \frac{N}{M+N}X$$

where $X(t)$ is the number of grams of chemical C formed.
The law of mass action states that when temperature is constant, the rate at which two substances react is proportional to the amounts of each that are untransformed at time t:

$$\frac{\mathrm{d}X}{\mathrm{d}t} \propto \left(a - \frac{M}{M+N}X\right)\left(b - \frac{N}{M+N}X\right)$$

Factoring out $M/(M+N)$ from the first factor and $N/(M+N)$ from the second and introducing constant of proportionality $k > 0$, this can be rewritten as

$$\frac{\mathrm{d}X}{\mathrm{d}t} = k(\alpha - X)(\beta - X)$$

where

$$\alpha = a\frac{M+N}{M} \qquad \text{and} \qquad \beta = b\frac{M+N}{N}$$

A chemical reaction governed by this nonlinear De is said to be a **second-order reaction**.

3.3 Modeling with Systems of First-Order Differential Equations

Linear/Nonlinear Systems

A system of two related first-order DEs may be

$$\frac{\mathrm{d}x}{\mathrm{d}t} = g_1(t,x,y) \qquad\qquad \frac{\mathrm{d}y}{\mathrm{d}t} = g_2(t,x,y)$$

When g_1 and g_2 are linear in x and y, being of the forms

$$g_1(t,x,y) = c_1x + c_2y + f_1(t) \qquad\qquad g_2(t,x,y) = c_3x + c_4y + f_2(t)$$

where the coefficients c_i may depend on t, the system is said to be **linear**. It is otherwise **nonlinear**.

Radioactive Series

When a substance decays via radioactivity, it generally doesn't simply transmute in a single step into a stable substance; a **radioactive decay series** is the process of continuous decaying into gradually more stable elements.
Schematically, a radioactive series may be described as

$$X \xrightarrow{-\lambda_1} Y \xrightarrow{-\lambda_2} Z$$

where

$$k_1 = -\lambda_1 < 0 \qquad \text{and} \qquad k_2 = -\lambda_2 < 0$$

are the decay constants of substances X and Y respectively and Z is a stable element. Suppose as well that $x(t)$, $y(t)$, and $z(t)$ denote the amounts os substances X, Y, and Z remaining at time t. The decay of X is described by

$$\frac{\mathrm{d}x}{\mathrm{d}t} = -\lambda_1 x$$

while that of Y is the net rate

$$\frac{\mathrm{d}y}{\mathrm{d}t} = \lambda_1 x - \lambda_2 y$$

as Y is *gaining* atoms from the decay of X while *losing* them due to its own decay.
As Z is a stable element, its aggregation is simply from the decay of Y:

$$\frac{\mathrm{d}z}{\mathrm{d}t} = \lambda_2 y$$

These three first-order DEs compose a linear system that models the radioactive decay series of 3 elements.

A Predator-Prey Model

Suppose that two species interact within the same ecosystem and that one eats only vegetation while the other preys only on the former; the latter is the predator, the former the prey. Let $x(t)$ denote the predator population and $y(t)$ denote the prey population. When there are no prey, the decline in predators would decline corresponding to

$$\frac{\mathrm{d}x}{\mathrm{d}t} = -ax, \quad a > 0$$

When there are prey in the environment it seems reasonable that the number of interactions between the species would be jointly proportional to their populations. So when prey are present, the predator population would increase at rate $bxy, b > 0$. Adding this to the last equation,

$$\frac{\mathrm{d}x}{\mathrm{d}t} = -ax + bxy$$

If there are no predators, the prey thrive, growing proportionally to the population:

$$\frac{\mathrm{d}y}{\mathrm{d}t} = dy, \quad d > 0$$

When predators are present, though, the prey population would decline at a rate modeled by cxy, decreasing by the rate at which they are eaten in their encounters:

$$\frac{\mathrm{d}y}{\mathrm{d}t} = dy - cxy$$

These formula constitute the **Lotka-Volterra predator-prey model**:

$$\frac{\mathrm{d}x}{\mathrm{d}t} = -ax + bxy = x(-a + by) \qquad\qquad \frac{\mathrm{d}y}{\mathrm{d}t} = dy - cxy = y(d - cx)$$

where a, b, c, and d are positive constant.
Apart from two constant solutions, $x(t) = 0$, $y(t) = 0$ and $x(t) = d/c$, $y(t) = a/b$, this system cannot be solved in terms of elementary functions.

Competition Models

Suppose two different species occupy the same ecosystem, competing for resources. In isolation, assume that the rate at which each population grows is respectively

$$\frac{\mathrm{d}x}{\mathrm{d}t} = ax \qquad \text{and} \qquad \frac{\mathrm{d}y}{\mathrm{d}t} = cy$$

As they are in direct competition, it may be assumed that each rate is diminished by the mere existence of the other population, providing the system

$$\frac{\mathrm{d}x}{\mathrm{d}t} = ax - by \qquad\qquad \frac{\mathrm{d}y}{\mathrm{d}t} = cy - dx$$

where a, b, c, and d are positive constants.
If the growth rate is instead affected proportionally to the number of interactions, the resulting system would be

$$\frac{\mathrm{d}x}{\mathrm{d}t} = ax - bxy \qquad\qquad \frac{\mathrm{d}y}{\mathrm{d}t} = cy - dxy$$

which is quite similar to the Lotka-Volterra predator-prey model.
It may be more realistic to replace the isolated rates with logistic models rather than exponential ones, making them

$$\frac{\mathrm{d}x}{\mathrm{d}t} = a_1x - b_1x^2 \qquad \text{and} \qquad \frac{\mathrm{d}y}{\mathrm{d}t} = a_2y - b_2y^2$$

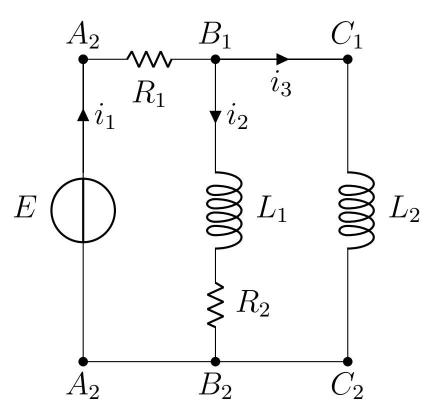
which results in another nonlinear model

$$\begin{aligned}\frac{\mathrm{d}x}{\mathrm{d}t} &= a_1x - b_1x^2 - c_1xy = x(a_1 - b_1x - c_1y)\\ \frac{\mathrm{d}y}{\mathrm{d}t} &= a_2y - b_2y^2 - c_2xy = y(a_2 - b_2 - c_2x)\end{aligned}$$

in which all coefficients are positive.
All of these models are called **competition models**.

Networks

An electrical network with more than one loop such as



results in simultaneous DEs. In this case, the current $i_1(t)$ splits in two at one of the network's *branch point* B_1. **Kirchhoff's first law** shows that

$$i_1(t) = i_2(t) + i_3(t)$$

Kirchhoff's second law can also be applied to each loop. Summing the voltage drops across each part of loop $A_1B_1B_2A_2A_2A_1$ gives

$$E(t) = i_1R_1 + L_1\frac{\mathrm{d}i_2}{\mathrm{d}t} + i_2R_2$$

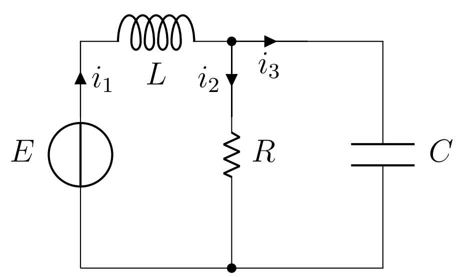
Doing the same for loop $A_1B_1C_1C_2B_2A_2A_1$ results in

$$E(t) = i_1R_1 + L_2\frac{\mathrm{d}i_3}{\mathrm{d}t}$$

Using the first derived equation to eliminate i_1 in the sums yields a linear system of two first order equations:

$$\begin{aligned} L_1\frac{\mathrm{d}i_2}{\mathrm{d}t} + (R_1+R_2)i_2 + R_1i_3 &= E(t) \\ L_3\frac{\mathrm{d}i_3}{\mathrm{d}t} + R_1i_2 + R_1I_3 &= E(T) \end{aligned}$$

Similarly,



results in the system

$$\begin{aligned} L\frac{\mathrm{d}i_1}{\mathrm{d}t} + Ri_2 &= E(t) \\ RC\frac{\mathrm{d}i_2}{\mathrm{d}t} + i_2 - i_1 &= 0 \end{aligned}$$

Chapter 4

Higher-Order Linear Equtaions

4.1 Preliminary Theory — Linear Equations

4.1.1 Initial-Value and Boundary-Value Problems

4.1.2 Homogenous Equations

4.1.3 Nonhomogenous Equations

4.2 Reduction of Order

4.3 Homogenous Linear Equations with Constant Coefficients

4.4 Undetermined Coefficients — Superposition Approach

4.5 Variation of Parameters

4.6 Cauchy-Euler Equations

4.7 Green's Function

4.7.1 Initial-Value Problems

4.7.2 Boundary Value Problems

4.8 Solving Systems of DEs by Elimination

4.9 Nonlinear Differential Equations