

Exercise 4.1

task a)

```
In[61]:= ClearAll["Global`*"]
σ = 10;
b = 8 / 3;
r = 28;

xdot[x_, y_, z_] := σ * (y - x)
ydot[x_, y_, z_] := r * x - y - x * z
zdot[x_, y_, z_] := x * y - b * z

sol = Solve[{xdot[x, y, z] == 0, ydot[x, y, z] == 0, zdot[x, y, z] == 0}, {x, y, z}]

Out[68]= {{x -> 0, y -> 0, z -> 0}, {x -> -6 Sqrt[2], y -> -6 Sqrt[2], z -> 27}, {x -> 6 Sqrt[2], y -> 6 Sqrt[2], z -> 27}}
```

```
Clear[eig1, eig2, eig3]
jacobi = D[{xdot[x, y, z], ydot[x, y, z], zdot[x, y, z]}, {{x, y, z}}];
eig1 = Eigenvalues[jacobi /. sol[[1]]]
eig2 = Eigenvalues[jacobi /. sol[[2]]]
eig3 = Eigenvalues[jacobi /. sol[[3]]]
```

```
Out[90]= {1/2 (-11 - Sqrt[1201]), 1/2 (-11 + Sqrt[1201]), -8/3}
```

```
Out[91]= {{3r -13.9..., 3r 0.0940... + 10.2... i, 3r 0.0940... - 10.2... i}}
```

```
Out[92]= {{3r -13.9..., 3r 0.0940... + 10.2... i, 3r 0.0940... - 10.2... i}}
```

For a fixed point to be stable, we need ALL $\text{Re}(\lambda) < 0$, thus this system only has unstable fixed points.

task b)

```

ClearAll["Global`*"]

σ = 10;
b = 8 / 3;
r = 28;

xdot[x_, y_, z_] := σ (y - x)
ydot[x_, y_, z_] := r x - y - x z
zdot[x_, y_, z_] := x y - b z

initialConditions = {x[0] == 0.1, y[0] == 0.1, z[0] == 0.1};
timeRange = {t, 0, 100};

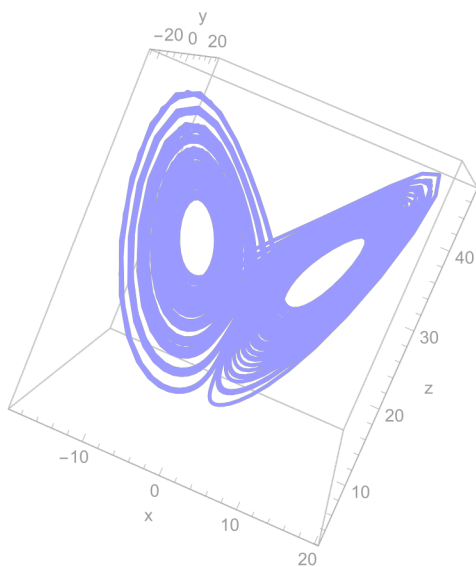
lorenzEquations = {
  x'[t] == xdot[x[t], y[t], z[t]],
  y'[t] == ydot[x[t], y[t], z[t]],
  z'[t] == zdot[x[t], y[t], z[t]],
  initialConditions};

sol = NDSolve[lorenzEquations, {x, y, z}, timeRange];

ParametricPlot3D[
  Evaluate[{x[t], y[t], z[t]} /. sol], {t, 20, 100},
  PlotRange → All,
  AxesLabel → {"x", "y", "z"},
  PlotStyle → {Thick, Blue}]

```

Out[166]=



task c)

```

ClearAll["Global`*"]
xdot[x_, y_, z_] :=  $\sigma$  * (y - x);
ydot[x_, y_, z_] := r * x - y - x * z;
zdot[x_, y_, z_] := x * y - b * z;

```

```

jacobi = D[{xdot[x, y, z], ydot[x, y, z], zdot[x, y, z]}, {{x, y, z}}]

```

```

Out[194]=
{{{- $\sigma$ ,  $\sigma$ , 0}, {r - z, -1, -x}, {y, x, -b}}}

```

task d)

```

In[195]:=
Tr[jacobi]

```

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Out[195]=
-1 - b -  $\sigma$ 

```