

# Post Calculus

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# 1 Linear Algebra

## §1.1 Eigenvectors and Eigenvalues

**Definition 1.1.1.** A homogeneous linear system is one where  $\mathbf{Ax} = \mathbf{0}$ .

The trivial solution is when  $\mathbf{x} = \mathbf{0}$ . Non-trivial solutions exist iff  $\det(\mathbf{A}) = 0$ .

### Theorem 1.1.2

Let  $\mathbf{A}$  be a square matrix.

$$\mathbf{A}\vec{\mathbf{v}} = \lambda\vec{\mathbf{v}}$$

if and only if  $\vec{\mathbf{v}}$  is an eigenvector and  $\lambda$  is an eigenvalue.

We notice that

$$\begin{aligned}\mathbf{A}\vec{\mathbf{v}} = \lambda\vec{\mathbf{v}} &\implies \mathbf{A}\vec{\mathbf{v}} = \lambda\mathbf{I}\vec{\mathbf{v}} \\ &\implies \vec{\mathbf{v}}(\mathbf{A} - \lambda\mathbf{I}) = \mathbf{0} \\ &\implies \det(\mathbf{A} - \lambda\mathbf{I}) = 0.\end{aligned}$$

The result above is known as the **characteristic equation**.

### Example 1.1.3

Let

$$\mathbf{A} = \begin{bmatrix} 0 & 1 \\ -4 & 0 \end{bmatrix},$$

find the eigenvalues and eigenvectors of  $\mathbf{A}$ .

We first notice that  $\det(\mathbf{A} - \lambda\mathbf{I}) = 0$ . Meaning that

$$\det\left(\begin{bmatrix} -\lambda & 1 \\ -4 & -\lambda \end{bmatrix}\right) = 0,$$

implying that  $\lambda^2 + 4 = 0$ . Thus,  $\lambda = \pm 2i$ . For  $\lambda_1 = 2i$ , we have

$$\begin{bmatrix} -2i & 1 \\ -4 & -2i \end{bmatrix} \vec{\mathbf{v}} = \mathbf{0}.$$

By gaussian elimination we arrive at the first eigenvector

$$\vec{\mathbf{v}}_1 = \begin{pmatrix} 1 \\ 2i \end{pmatrix}.$$

Similarly

$$\vec{\mathbf{v}}_2 = \begin{pmatrix} 1 \\ -2i \end{pmatrix}$$

for  $\lambda_2 = -2i$ .

## §1.2 Diagonalization

For  $\mathbf{y} = \mathbf{A}\mathbf{x}$ , assume  $\mathbf{A}$  has a basis of eigenvectors  $\mathbf{x}_1, \mathbf{x}_2, \dots, \mathbf{x}_n$ , with corresponding eigenvalues  $\lambda_1, \lambda_2, \dots, \lambda_n$ , and let the matrix

$$\mathbf{P} = \begin{pmatrix} \mathbf{x}_1 & \mathbf{x}_2 & \cdots & \mathbf{x}_n \end{pmatrix}$$

be a transformation matrix. Let

$$\mathbf{y} = \mathbf{P}\mathbf{y}' \text{ and } \mathbf{x} = \mathbf{P}\mathbf{x}'.$$

We can then write a new linear system relating  $\mathbf{y}'$  and  $\mathbf{x}'$ , giving

$$\begin{aligned} \mathbf{P}\mathbf{y}' &= \mathbf{A}\mathbf{P}\mathbf{x}' \implies \mathbf{P}^{-1}\mathbf{P}\mathbf{y}' = \mathbf{P}^{-1}\mathbf{A}\mathbf{P}\mathbf{P}^{-1}\mathbf{P}\mathbf{x}' \\ &\implies \mathbf{y}' = (\mathbf{P}^{-1}\mathbf{A}\mathbf{P})\mathbf{x}', \end{aligned}$$

where  $\mathbf{D} = (\mathbf{P}^{-1}\mathbf{A}\mathbf{P})$  is a diagonal matrix such that the diagonals turn out to be the eigenvalues of  $\mathbf{A}$ .

**Remark 1.2.1.** In order to find the diagonalization matrix, begin by finding the eigenvalues and eigenvectors of  $\mathbf{A}$ . Then find  $\mathbf{P}$  from the eigenvectors. The diagonalization matrix follows.

### Example 1.2.2

Diagonalize

$$\begin{bmatrix} 7/4 & -\sqrt{3}/4 \\ -\sqrt{3}/4 & 5/4 \end{bmatrix}.$$

## §1.3 Rotating Conics

Let  $Q$  be a quadratic form such that

$$Q = ax_1^2 + (b+c)x_1x_2 + dx_2^2.$$

We can express this as

$$Q = \mathbf{x}^T \mathbf{A} \mathbf{x} = \begin{bmatrix} x_1 & x_2 \end{bmatrix} \begin{bmatrix} a & b \\ c & d \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \end{bmatrix},$$

where

$$\mathbf{A} = \begin{bmatrix} a & b \\ c & d \end{bmatrix}.$$

We can convert the quadratic form to the canonical form by using the diagonalized matrix of  $\mathbf{A}$ :

$$C = \begin{bmatrix} x'_1 & x'_2 \end{bmatrix} \mathbf{D} \begin{bmatrix} x'_1 \\ x'_2 \end{bmatrix}.$$

Additionally, note that the transformation matrix is the rotation matrix, meaning that

$$\mathbf{P} = \begin{bmatrix} \cos x & -\sin x \\ \sin x & \cos x \end{bmatrix}.$$

**Theorem 1.3.1**

Let  $Q_n$  be a quadratic form with  $n$  dimensions and  $C_n$  the corresponding canonical form. Then, for an  $n \times n$  matrix  $\mathbf{A}$  and its diagonalized matrix  $\mathbf{D}$ ,

$$Q_n = \begin{bmatrix} x_1 & x_2 & \cdots & x_n \end{bmatrix} \mathbf{A} \begin{bmatrix} x_1 \\ x_2 \\ \vdots \\ x_n \end{bmatrix},$$

$$C_n = \begin{bmatrix} x'_1 & x'_2 & \cdots & x'_n \end{bmatrix} \mathbf{D} \begin{bmatrix} x'_1 \\ x'_2 \\ \vdots \\ x'_n \end{bmatrix}.$$

If any linear terms are present, they can be expressed as the product of the coefficient matrix and the matrix with each variable. So,

$$a_1x_1 + a_2x_2 + \cdots + a_nx_n = \begin{bmatrix} a_1 & a_2 & \cdots & a_n \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \\ \vdots \\ x_n \end{bmatrix}.$$

**Exercise 1.3.2.**





# 2 3D Optimization

## §2.1 Partial Derivatives

Let  $f(x, y, z) = 2x^2 + 3y^2 + z^2$ . Partial derivatives treat the other variables as constants. Thus,

$$\frac{\partial f}{\partial x} = 4x, \quad \frac{\partial f}{\partial y} = 6y, \quad \frac{\partial f}{\partial z} = 2.$$

**Definition 2.1.1.** The **gradient vector** for a function  $f$  is

$$\nabla f(p) = \begin{bmatrix} \frac{\partial f}{\partial x_1}(p) \\ \vdots \\ \frac{\partial f}{\partial x_n}(p) \end{bmatrix}.$$

**Definition 2.1.2.** The **Hessian Matrix** is

$$\mathbf{H}_f = \begin{bmatrix} \frac{\partial^2 f}{\partial x_1^2} & \frac{\partial^2 f}{\partial x_1 \partial x_2} & \cdots & \frac{\partial^2 f}{\partial x_1 \partial x_n} \\ \frac{\partial^2 f}{\partial x_2 \partial x_1} & \frac{\partial^2 f}{\partial x_2^2} & \cdots & \frac{\partial^2 f}{\partial x_2 \partial x_n} \\ \vdots & \vdots & \ddots & \vdots \\ \frac{\partial^2 f}{\partial x_n \partial x_1} & \frac{\partial^2 f}{\partial x_n \partial x_2} & \cdots & \frac{\partial^2 f}{\partial x_n^2} \end{bmatrix},$$

### Theorem 2.1.3 (Schwarz's Theorem)

For a function  $f : \Omega \rightarrow \mathbb{R}$  defined on a set  $\Omega \subset \mathbb{R}^n$ , if  $\mathbf{p} \in \mathbb{R}^n$  is a point such that some neighborhood of  $\mathbf{p}$  is contained in  $\Omega$  and  $f$  has continuous second partial derivatives at the point  $\mathbf{p}$ , then  $\forall i, j \in \{1, 2, \dots, n\}$

$$\frac{\partial^2}{\partial x_i \partial x_j} f(\mathbf{p}) = \frac{\partial^2}{\partial x_j \partial x_i} f(\mathbf{p}).$$

*Proof.* The proof is left as a search on wikipedia :p. □

### Example 2.1.4

Find the gradient and hessian matrix of  $f(x, y, z) = 2x^2 + 3y^2 + z^2$ .

*Solution.* We find that

$$\nabla f = \begin{bmatrix} \frac{\partial f}{\partial x} \\ \frac{\partial f}{\partial y} \\ \frac{\partial f}{\partial z} \end{bmatrix} = \begin{bmatrix} 4x \\ 6y \\ 2z \end{bmatrix}$$

and

$$\mathbf{H}_f = \begin{bmatrix} 4 & 0 & 0 \\ 0 & 6 & 0 \\ 0 & 0 & 2 \end{bmatrix}.$$

□

### Example 2.1.5

Find the gradient and hessian matrix of  $f(x, y) = x^2 - 3xy + y^2$ .

*Solution.* We find that

$$\nabla f = \begin{bmatrix} \frac{\partial f}{\partial x} \\ \frac{\partial f}{\partial y} \end{bmatrix} = \begin{bmatrix} 2x - 3y \\ 2y - 3x \end{bmatrix},$$

$$\mathbf{H}_f = \begin{bmatrix} 2 & -3 \\ -3 & 2 \end{bmatrix}.$$

□

### Example 2.1.6

Find the gradient and hessian matrix  $f(x_1, x_2, x_3) = 9x_1^2 + 7x_2^2 + 3x_3^2 - 2x_1x_2 + 4x_1x_3 - 6x_2x_3$ .

*Solution.* We find that

$$\nabla f = \begin{bmatrix} 18x_1 - 2x_2 + 4x_3 \\ -2x_1 + 14x_2 - 6x_3 \\ 4x_1 - 6x_2 + 6x_3 \end{bmatrix},$$

$$\mathbf{H}_f = \begin{bmatrix} 18 & -2 & 4 \\ -2 & 14 & -6 \\ 4 & -6 & 6 \end{bmatrix}.$$

□

### Example 2.1.7

Let  $x$  be a function of  $t$ . Find  $\frac{\partial f}{\partial x}$ ,  $\frac{\partial f}{\partial \dot{x}}$ ,  $\frac{\partial f}{\partial \ddot{x}}$ , and  $\frac{df}{dt}$ .

**Theorem 2.1.8** (Generalized Chain Rule)

Let  $w = f(x_1, x_2, \dots, x_m)$  be a differentiable function of  $m$  independent variables, and for each  $i \in \{1, \dots, m\}$ , let  $x_i = x_i(t_1, t_2, \dots, t_n)$  be a differentiable function of  $n$  independent variables. Then

$$\frac{\partial w}{\partial t_j} = \frac{\partial w}{\partial x_1} \frac{\partial x_1}{\partial t_j} + \frac{\partial w}{\partial x_2} \frac{\partial x_2}{\partial t_j} + \dots + \frac{\partial w}{\partial x_m} \frac{\partial x_m}{\partial t_j}$$

for any  $j \in \{1, \dots, n\}$ .

*Proof.* Deez nutz □

## §2.2 Tangent Planes

We proceed by finding the equation of the tangent plane to  $x^2 - y^2 - z^2 = 1$  at  $(1, 0, 0)$ . To begin, we find the gradient of  $f(x, y, z) = x^2 - y^2 - z^2$  to be

$$\nabla f(1, 0, 0) = \begin{bmatrix} 2 \\ 0 \\ 0 \end{bmatrix}.$$

Then, the "point-slope" form of a plane is

$$m_x(x - x_1) + m_y(y - y_1) + m_z(z - z_1) = 0.$$

Thus, we obtain the following tangent plane for our scenario:  $2(x - 1) = 0$ .

## §2.3 Unconstrained Optimization

**Definition 2.3.1.** A **stationary point** is a critical point in higher dimensions. They can be found from the solution to the system of equations that results from letting the gradient equal zero.

**Definition 2.3.2.** A hessian is called **positive definite** if all the eigenvalues are positive.

**Definition 2.3.3.** A hessian is called **negative definite** if all the eigenvalues are negative.

**Definition 2.3.4.** A hessian is called **positive semidefinite** if all the eigenvalues are nonnegative and there exists at least one eigenvalue that is 0.

**Definition 2.3.5.** A hessian is called **negative semidefinite** if all the eigenvalues are nonpositive and there exists at least one eigenvalue that is 0.

**Definition 2.3.6.** A point is a **saddle point** if the hessian has negative and positive eigenvalues.

As an alternative to the second derivative test in determining if a critical point is a max, min or an inflection point, the **hessian** will be used to determine if a stationary point is a max, min or inflection point.

**Theorem 2.3.7** (Second Partial Derivative Test)

We can determine if the hessian is "positive" or "negative" by taking a look at its eigen values. Let  $\mathbf{H}_f$  be the hessian for  $f$ , a differentiable function of  $n$  independent variables. Also, let  $\Lambda = \{\lambda_i | 1 \leq i \leq n\}$  be the set of the eigenvalues of  $\mathbf{H}_f$ . If all elements in  $\Lambda$  are positive, then the hessian is called **positive definite**, giving a minimum. If all elements in  $\Lambda$  are negative, then the hessian is called **negative definite**, giving a maximum. If  $\lambda_i \geq 0$ ,  $\mathbf{H}_f$  is called **positive semidefinite**. If  $\lambda_i \leq 0$ ,  $\mathbf{H}_f$  is called **negative semidefinite**. If one eigenvalue is positive and one eigenvalue is negative, we have a **saddle point**.

**Example 2.3.8**

Find the critical points of  $f(x_1, x_2) = x_1^2 - 2x_1x_2 + 4x_2^2$ .

*Proof.* We begin by finding the gradient of  $f$ . This is

$$\nabla f = \begin{bmatrix} 2x_1 - 2x_2 \\ -2x_1 + 8x_2 \end{bmatrix}.$$

Setting the gradient to zero, we get the following system of equations:

$$\begin{aligned} 2x_1 - 2x_2 &= 0 \\ -2x_1 + 8x_2 &= 0. \end{aligned}$$

This gives  $(x_1, x_2) = (0, 0)$ . The hessian,  $\mathbf{H}_f$  of  $f$  is

$$\mathbf{H}_f = \begin{bmatrix} 2 & -2 \\ -2 & 8 \end{bmatrix}.$$

Since the eigen values of this hessian are both positive, we have a minimum.  $\square$

**Example 2.3.9**

Find the critical points of  $f(x_1, x_2) = -x_1^2 + 2x_1x_2 + 3x_2^2 + 8x_1$ .

*Proof.* We begin by finding the gradient of  $f$ . This is

$$\nabla f = \begin{bmatrix} -2x_1 + 2x_2 + 8 \\ 2x_1 + 6x_2 \end{bmatrix}.$$

Setting the gradient to zero, we get the following system of equations:

$$\begin{aligned} -2x_1 + 2x_2 &= -8 \\ 2x_1 + 6x_2 &= 0. \end{aligned}$$

Solving gives  $(x_1, x_2) = (-3, 1)$ . The hessian,  $\mathbf{H}_f$ , of  $f$  is

$$\mathbf{H}_f = \begin{bmatrix} -2 & 2 \\ 2 & 6 \end{bmatrix}.$$

Since one of the eigenvalues of this hessian is positive and the other is negative, we have a saddle point.  $\square$

**Example 2.3.10**

Find the critical points of  $f(x_1, x_2) = (x_1 - x_2^2)(x_1 - 3x_2^2)$ .

*Proof.* To begin, we distribute to get  $f(x_1, x_2) = x_1^2 - 4x_1x_2^2 + 3x_2^4$ . The gradient of  $f$  is then

$$\nabla f = \begin{bmatrix} 2x_1 - 4x_2^2 \\ -8x_1x_2 + 12x_2^3 \end{bmatrix}.$$

Setting the gradient to zero and solving the resulting system of equations, we get the following critical point  $(x_1, x_2) = (0, 0)$ . The hessian of  $f$  is

$$\mathbf{H}_f = \begin{bmatrix} 2 & -8x_2 \\ -8x_2 & -8x_1 + 36x_2^2 \end{bmatrix} = \begin{bmatrix} 2 & 0 \\ 0 & 0 \end{bmatrix}.$$

Since one eigenvalue is positive and the other is equal to 0, the hessian is positive semidefinite.  $\square$

**Example 2.3.11**

Kartik and Monica invested \$20,000 in the design and the development of a new product. They can manufacture it for \$2 per unit. They hired marketing consultants to determine the relation between selling price, the amount spent on advertising, and the number of units that would be sold as a result of the first two combined. The company determined that units sold would follow the equation

$$2000 + 4\sqrt{a} - 20p.$$

Determine the profit that Felicia and Megan will make as a function of the money spent on advertising,  $a$ , and the price of the product,  $p$ . Maximize that profit.

*Proof.* We first identify that the revenue gained from sales would be  $p(2000 + 4\sqrt{a} - 20p)$ . Then, the costs would be  $20000 + 2(2000 + 4\sqrt{a} - 20p) + a$ . Taking the difference, we get the profit  $P$  being

$$\begin{aligned} P(a, p) &= p(2000 + 4\sqrt{a} - 20p) - 20000 - 2(2000 + 4\sqrt{a} - 20p) - a \\ &= 2040p + 4p\sqrt{a} - 20p^2 - 24000 - 8\sqrt{a} - a. \end{aligned}$$

The gradient of  $P$  is

$$\nabla P = \begin{bmatrix} \frac{2p-4}{\sqrt{a}} - 1 \\ -40p + 4\sqrt{a} + 2040 \end{bmatrix}.$$

Setting the gradient to 0 and solving the resulting system of equations, we get that  $p = 63.25$  and  $a = 15006.25$ . The maximum profit is  $\boxed{\$40025}$ .  $\square$

**§2.4 Constrained Optimization**

Equality and Inequality constraints

**Definition 2.4.1.** The **Lagrangian** is

$$L(x, \lambda) = f(x) + \sum_{i=1}^m \lambda_i (b_i - g_i(x)),$$

where  $g_i(x)$  are constraints.

**Example 2.4.2**

Maximize  $f(x_1, x_2) = 5 - (x_1 - 2)^2 - 2(x_2 - 1)^2$  subject to  $x_1 + 4x_2 = 3$ .

*Proof.* We get

$$\begin{aligned} \mathcal{L}(x, \lambda) &= f(x_1, x_2) + \lambda(x_1 + 4x_2 - 3) \\ &= 5 - x_1^2 + 4x_1 - 4 - 2x_2^2 + 4x_2 - 2 + \lambda(x_1 + 4x_2 - 3) \\ &= -x_1^2 - 2x_2^2 + 4x_1 + 4x_2 - 1 + \lambda(x_1 + 4x_2 - 3) \end{aligned}$$

Thus

$$\nabla \mathcal{L} = \begin{bmatrix} -2x_1 + \lambda + 4 \\ -4x_2 + 4\lambda + 4 \\ x_1 + 4x_2 - 3 \end{bmatrix} = 0$$

We get  $(x_1, x_2, \lambda) = (5/3, 1/3, -2/3)$ . Thus our critical point is  $\boxed{(5/3, 1/3, 4)}$ .  $\square$

**Example 2.4.3**

Let the sun be located at the origin of a coordinate plane. How close does Halley's comet come to the sun on its orbit?

$$171.725x^2 + 171.725y^2 + 297.37xy + 557.178x - 557.178y - 562.867 = 0.$$

*Proof.* We seek to optimize the distance from the comet to the sun. Thus, we seek to optimize  $f(x, y) = x^2 + y^2$ . Optimization with the lagrangian follows, where

$$\mathcal{L} = x^2 + y^2 - \lambda().$$

$\square$

**Example 2.4.4**

Minimize  $L(x) = x_1 e^{-(x_1^2 + x_2^2)} + \frac{x_1^2 + x_2^2}{20}$  subject to  $f(x) = \frac{x_1 x_2}{2} + (x_1^2 + 2)^2 + (x_1^2 - 2)^2/2 - 2 \leq 0$ .

*Proof.* We find that

$$\nabla L = \begin{bmatrix} e^{-(x_1^2 + x_2^2)} - 2x_1^2 e^{-(x_1^2 + x_2^2)} + x_1/10 \\ -2x_1 x_2 e^{-(x_1^2 + x_2^2)} + x_2/10 \end{bmatrix} = 0$$

We find that the critical points are  $(-1/2, \sqrt{\ln(10) - 1/4})$  and  $(-1/2, -\sqrt{\ln(10) - 1/4})$ .  $\square$

# 3 Differential Equations

## §3.1 Separable Differential Equations

A separable differential equation can be simplified to the form:

$$g(y)y' = f(x) \implies g(y) dy = f(x) dx,$$

where  $f$  and  $g$  are functions of  $x$  and  $y$  respectively. Letting  $G'(y) = g(y)$  and  $F'(x) = f(x)$  and taking the integral of both sides of the differential equation, we get

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

for some constant  $C$ . Using a separation of variables is most helpful as a first try when attempting first-order linear ordinary differential equations. It is also used as a very useful intermediate step in solving more complex differential equations. We go more in detail later in the chapter.

### Example 3.1.1 (Separable Differential Equation)

Solve for  $y$ :

$$\frac{dy}{dx} = x^2y - 2xy.$$

*Solution.* Separating the variables, we see that  $\frac{1}{y} dy = (x^2 - 2x) dx$ . Taking the integral of both sides yields

$$\ln y = \frac{1}{3}x^3 - x^2 + A \implies y = Ae^{\frac{1}{3}x^3 - x^2}.$$

□

**Question 3.1.2.** What is  $y$  when given the initial condition  $y(0) = e$ ?

## §3.2 Homogeneous Ordinary Differential Equations

The general form of a linear ordinary differential equation (ODE) is

$$a_n y^{(n)} + a_{n-1} y^{(n-1)} + \cdots + a_1 y' + a_0 y = f(x),$$

where  $a_i \in \mathbb{R}[x]$  for  $i \in \{0, 1, \dots, n\}$  and  $y^{(j)}$  denotes the  $j$ th derivative of  $y$ . It is then said that this ODE has **order**  $n$  since it is the highest derivative in the equation. An ODE is said to be **homogenous** if  $f(x) = 0$ . Otherwise, it is said to be a **nonhomogeneous** ODE. The most common method of approaching homogeneous ODEs is ansatz. This is an educated guess that is made to help solve a problem. This will become apparent not only in homogeneous ODEs but more complex ones as well.

**Example 3.2.1** (Homogeneous ODE)Solve for  $y$ :

$$y'' + 7y' + 12y = 0.$$

*Solution.* Functions of the form  $y = e^{mx}$  are an educated guess for solving homogeneous ODEs. So, letting  $y = e^{mx}$  means  $y' = me^{mx}$  and  $y'' = m^2e^{mx}$ . Plugging these in our differential equation,

$$\begin{aligned} m^2e^{mx} + 7me^{mx} + 12e^{mx} &= 0 \\ e^{mx}(m^2 + 7m + 12) &= 0 \\ e^{mx}(m + 4)(m + 3) &= 0. \end{aligned}$$

Therefore,  $m = -4, -3$ , implying that  $y_1 = C_1e^{-4x}$  and  $y_2 = C_2e^{-3x}$ . This means that our solution of the differential equation is

$$y_h = y_1 + y_2 = C_1e^{-4x} + C_2e^{-3x}.$$

□

At first, it might be puzzling why we consider  $y = e^{mx}$  to be an educated guess for solving homogeneous ODEs with constant coefficients. However, let us consider the following first-order differential equation

$$y' + ky = 0 \implies y' = -ky.$$

Here, it is natural to guess that  $y = e^{mx}$  because  $e^{mx}$  is the only function where its derivative is equal to some scalar multiple of itself. So, for other homogeneous ODEs with constant coefficient and of higher degree, we also use the guess as a means of finding the general solution.

**Exercise 3.2.2** (Homogeneous ODE with initial values).

$$y'' + y' - 2y = 0, \quad y(0) = 4, \quad y'(0) = -5.$$

Now, we consider what happens if we get a polynomial with repeated roots or if we are already given a solution to the differential equation.

**Example 3.2.3** (Homogeneous ODE with repeated roots)Solve for  $y$ :

$$y'' + 4y' + 4y = 0.$$

*Solution.* Let  $y = e^{mx}$ . This means  $y' = me^{mx}$  and  $y'' = m^2e^{mx}$ . Plugging in, we get

$$\begin{aligned} m^2e^{mx} + 4me^{mx} + 4e^{mx} &= 0 \\ e^{mx}(m + 2)^2 &= 0. \end{aligned}$$

Therefore, the first fundamental solution is  $y_1 = e^{-2x}$ . However, it is not clear what the second fundamental solution to this differential equation is. In order to determine this, we use the method of **reduction of order**. This involves letting the second fundamental solution being the product of  $y_1$  and some function of  $x$ , say  $f(x)$ . So, let  $y_2 = f(x) \cdot y_1$ .



Now, we seek to find what  $f(x)$  is. Thus, we want to find the first and second derivatives of  $y_2$  in order to plug it back into the original differential equation. This will aid us in finding out more information regarding  $f(x)$ . Therefore, we have

$$\begin{aligned} y_2' &= f'(x)y_1 + f(x)y_1' \\ &= f'(x)e^{-2x} - 2f(x)e^{-2x} \\ y_2'' &= f''(x)y_1 + 2f'(x)y_1' + f(x)y_1'' \\ &= f''(x)e^{-2x} - 4f'(x)e^{-2x} + 4f(x)e^{-2x}. \end{aligned}$$

Plugging this into the original differential equation and simplifying fully yields  $f''(x) = 0$ . Now, let  $g(x) = f'(x)$ . This means  $g'(x) = f''(x)$ . So,  $g'(x) = 0$ . Solving for  $g(x)$  we get  $g(x) = A$ . Therefore,  $f'(x) = A$ . Solving for  $f(x)$  then gives  $f(x) = Ax + B$ . Thus,

$$y_2 = (Ax + B)e^{-2x} \implies y_2 = xe^{-2x}$$

since  $y_2$  must be linearly independent from  $y_1$ . Finally, we find the solution to the differential equation to be

$$y = c_1y_1 + c_2y_2 = c_1e^{-2x} + c_2xe^{-2x}.$$

□

### Theorem 3.2.4 (Reduction of Order)

Consider a general homogeneous linear ODE of order two:

$$y''(x) + p(x)y'(x) + q(x)y(x) = 0$$

and suppose  $y_1(x)$  is one solution to the differential equation. Then the second solution to the differential equation is

$$y_2(x) = y_1(x) \int \frac{u(x)}{[y_1(x)]^2} dx,$$

where  $u(x) = e^{-\int p(x) dx}$ .

*Proof.* We assume the second solution is of the form  $y_2(x) = f(x)y_1(x)$  for some function  $f$ . Thus,

$$y_2' = f'y_1 + fy_1' \quad y_2'' = f''y_1 + 2f'y_1' + fy_1''.$$

Substituting these expressions back into the original differential equation, we get

$$f''y_1 + 2f'y_1' + fy_1'' + p(f'y_1 + fy_1') + qfy_1 = 0.$$

Rearranging these terms, we obtain

$$f(y_1'' + py_1' + qy_1) + f''y_1 + 2f'y_1' + pf'y_1 = 0.$$

Notice that the term in the parentheses becomes 0 since  $y_1$  is a solution to the differential equation. Therefore, we are simply left with

$$f''y_1 + 2f'y_1' + pf'y_1 = 0.$$

Rearranging and letting  $g(x) = f'(x)$ ,

$$g'(x) = -g(x) \left( 2 \frac{y_1'(x)}{y_1(x)} + p(x) \right).$$

Now, we simply have a first-order ODE in terms of  $g(x)$ . It can then be shown that  $f(x) = \int \frac{u(x)}{[y_1(x)]^2} dx$  where  $u(x) = e^{-\int p(x) dx}$ . It then follows that

$$y_2(x) = y_1(x) \int \frac{u(x)}{[y_1(x)]^2} dx.$$

□

### Corollary 3.2.5 (Reduction of Order with Constant Coefficients)

Consider a homogeneous linear ODE with constant coefficients:

$$ay''(x) + by'(x) + cy(x) = 0$$

where  $a, b, c \in \mathbb{R} \setminus \{0\}$  and suppose the discriminant,  $b^2 - 4ac$ , vanishes due to the presence of a repeated root in the characteristic equation. Additionally suppose  $y_1(x)$  is one solution to the differential equation. Then the second solution to the differential equation is  $y_2(x) = xy_1(x)$ .

*Proof.* Letting  $y = e^{mx}$  and solving for  $m$  from the resulting characteristic equation gives  $m = -\frac{b}{2a}$ . Therefore  $y_1(x) = e^{-\frac{b}{2a}x}$ . □

### Example 3.2.6 (Reduction of Order)

Solve for  $y$ :

$$y'' + y' + (1/4)y = 0; \quad y(0) = 3; \quad y'(0) = -3.5.$$

*Solution.* Let  $y = e^{mx}$ . This means  $y' = me^{mx}$  and  $y'' = m^2e^{mx}$ . Plugging in, we get

$$\begin{aligned} 4m^2e^{mx} + 4me^{mx} + e^{mx} &= 0 \\ e^{mx}(4m^2 + 4m + 1) &= 0 \\ e^{mx}(2m + 1)^2 &= 0. \end{aligned}$$

Therefore  $y_1 = e^{-x/2}$ . Then, by the general result of reduction of order on a homogeneous linear ODE with constant coefficients gives  $y_2 = x \cdot y_1$ . So, the solution to the differential equation is

$$y = c_1e^{-x/2} + c_2xe^{-x/2}$$

Using the initial values to solve for constants  $c_1$  and  $c_2$ , we finally find

$$y = 3e^{-x/2} - 2xe^{-x/2}.$$

□

**Example 3.2.7** (Reduction of Order)

$$y''' + 3y'' - 4y = 0.$$

*Solution.* Let  $y = e^{mx}$ . This mean  $y' = me^{mx}$  and  $y'' = m^2e^{mx}$ . Plugging in, we get

$$\begin{aligned} m^3e^{mx} + 3m^2e^{mx} - 4e^{mx} &= 0 \\ e^{mx} (m^3 + 3m^2 - 4) &= 0 \\ e^{mx} (m - 1)(m^2 + 4m + 4) &= 0 \\ e^{mx} (m - 1)(m + 2)^2 &= 0. \end{aligned}$$

Therefore,  $y_1 = e^x$ ,  $y_2 = e^{-2x}$ , and  $y_3 = xe^{-2x}$ . Thus,

$$y_h = c_1e^x + c_2e^{-2x} + c_3xe^{-2x}.$$

□

Thus far, we have examined ODEs which had characteristic equations with real roots. However, it may be the case that these characteristic equations obtain complex roots. The help of **euler's formula** helps to clear any complex numbers in the solution.

**Theorem 3.2.8** (Euler's Formula)

For any complex number  $x$ ,

$$e^{ix} = \cos x + i \sin x.$$

*Proof.* A taylor series expansion of both sides gives the result. □

**Example 3.2.9** (Complex Roots)

Solve for  $y$ :

$$y'' + 4y = 0.$$

*Solution.* Let  $y = e^{mx}$ . This means that  $y'' = m^2e^{mx}$ . Plugging in gives  $m = \pm 2i$ . Thus,

$$y = c_1e^{2ix} + c_2e^{-2ix}.$$

By Euler's Formula,

$$\begin{aligned} y &= c_1(\cos 2x + i \sin 2x) + c_2(\cos 2x - i \sin 2x) \\ y &= c_1 \cos 2x + c_2 \sin 2x. \end{aligned}$$

□

**Example 3.2.10** (Complex Roots)

$$y'' + 8y' + 25y = 0.$$

*Solution.* Let  $y = e^{mx}$ . This means that  $y' = me^{mx}$  and  $y'' = m^2e^{mx}$ . Plugging this in gives  $-4 \pm 3i$ . Thus,

$$\begin{aligned} y_h &= C_1 e^{(-4+3i)x} + C_2 e^{(-4-3i)x} \\ y_h &= e^{-4x} (C_1 e^{3ix} + C_2 e^{-3ix}) \\ y_h &= e^{-4x} (C_1 \cos(3x) + C_2 \sin(3x)). \end{aligned}$$

□

### §3.3 Nonhomogeneous Ordinary Differential Equations

A **nonhomogeneous** differential equation is of the form

$$a_n y^{(n)} + a_{n-1} y^{(n-1)} + \cdots + a_1 y' + a_0 y = f(x)$$

where  $a_i \in \mathbb{R}[x]$  for  $i \in \{1, 2, \dots, n\}$  and  $f(x) \neq 0$ . The general solution to a nonhomogeneous differential equation is  $y = y_h + y_p$ , where  $y_h$  is found from letting the left hand side equal 0 and the particular solution,  $y_p$ , is found by using one of two methods, namely **undetermined coefficients** or **variation of parameters**. Undetermined coefficients can only be used with differential equations with scalar coefficients while variation of parameters can be used with scalar or variable coefficients.

#### Theorem 3.3.1 (Undetermined Coefficients)

Consider the differential equation

$$a_2 y''(x) + a_1 y'(x) + a_0 y(x) = f(x).$$

In order to solve for the particular solution,  $y_p$ , we guess  $y_p$  based on the following table

$f(x)$	$y_p(x)$
$a e^{\beta x}$	$A e^{\beta x}$
$a \cos(\beta x)$	$A \cos(\beta x) + B \sin(\beta x)$
$b \sin(\beta x)$	$A \cos(\beta x) + B \sin(\beta x)$
$a \cos(\beta x) + b \sin(\beta x)$	$A \cos(\beta x) + B \sin(\beta x)$
$n$ th deg polynomial	$A_n x^n + A_{n-1} x^{n-1} + \cdots + A_0$

In addition, if  $f(x)$  is a linear combination of any of the forms above, then  $y_p(x)$  is also a linear combination of the guesses for each of the forms present in  $f(x)$ .

#### Example 3.3.2 (Undetermined Coefficients)

$$y'' - 4y' + 3y = e^{-x}; \quad y(0) = 1; \quad y'(0) = 0.$$

*Solution.* We first find  $y_h$  using  $y'' - 4y' + 3y = 0$ . Thus we obtain

$$y_h = C_1 e^x + C_2 e^{3x}.$$

Our guess for  $y_p = Ce^{-x}$ . Thus,  $y'_p = -Ce^{-x}$  and  $y''_p = Ce^{-x}$ . So, plugging this in, we get

$$\begin{aligned} Ce^{-x} + 4Ce^{-x} + 3Ce^{-x} &= e^{-x} \implies 8Ce^{-x} = e^{-x} \\ \implies C &= \frac{1}{8}. \end{aligned}$$

Therefore

$$y = y_h + y_p = C_1e^x + C_2e^{3x} + \frac{1}{8}e^{-x}.$$

Using the initial values, we find that

$$y = \frac{5}{4}e^x - \frac{3}{8}e^{3x} + \frac{1}{8}e^{-x}.$$

□

### Example 3.3.3 (Guessing Practice with Undetermined Coefficients)

$$y'' + 2y' + y = \cos(2x)$$

*Solution.* We first proceed to find  $y_h$ . We find that

$$y_h = C_1e^{-x} + C_2xe^{-x}.$$

We make the following guess:  $y_p = a \cos(2x) + b \sin(2x)$ . Solving for  $a$  and  $b$ , we find that  $y_p = -\frac{3}{25} \cos(2x) + \frac{4}{25} \sin(2x)$ . Therefore

$$y = C_1e^{-x} + C_2xe^{-x} - \frac{3}{25} \cos(2x) + \frac{4}{25} \sin(2x).$$

□

### Example 3.3.4 (Bad Guessing)

$$y'' + 4y' + 3y = e^{-x}.$$

*Solution.* We notice  $y_h = C_1e^{-x} + C_2e^{-3x}$ .  $y_p = Ce^{-x}$  is a bad guess since it is a term present in the homogeneous equation. So, we let  $y_p = Cxe^{-x}$ , which is a guess from the result of applying the reduction of order. Solving for  $C$ , we get that  $C = \frac{1}{2}$ . Therefore

$$y = C_1e^{-x} + C_2e^{-3x} + \frac{1}{2}xe^{-x}.$$

□

**Theorem 3.3.5** (Variation of Parameters)

The method of variation of parameters is a technique for finding a particular solution to a nonhomogeneous linear second order ODE:

$$y'' + P(x)y' + Q(x)y = R(x)$$

provided that the general solution of the corresponding homogeneous linear second order ODE:

$$y'' + P(x)y' + Q(x)y = 0$$

is already known. The particular solution is then

$$y_p = u(x)y_1(x) + v(x)y_2(x)$$

such that

$$u'(x) = -\frac{y_2 R(x)}{W(y_1, y_2)} \text{ and } v'(x) = \frac{y_1 R(x)}{W(y_1, y_2)},$$

where  $W(y_1, y_2)$  denotes the Wronskian of  $y_1$  and  $y_2$ .

*Proof.* First, we have

$$\begin{aligned} y'_p &= (u'y_1 + uy'_1) + (v'y_2 + vy'_2) \\ &= (uy'_1 + vy'_2) + (u'y_1 + v'y_2) \end{aligned}$$

by the product rule. □

**Example 3.3.6** (Variation of parameters)

$$y'' + 4y' + 4y = e^{-2x}/x^2.$$

*Solution.* We find that  $y_h = C_1 e^{-2x} + C_2 x e^{-2x}$ . Notice that the Wronskian is

$$w = \det \left( \begin{bmatrix} e^{-2x} & x e^{-2x} \\ -2e^{-2x} & e^{-2x} - 2x e^{-2x} \end{bmatrix} \right) = e^{-4x}.$$

Thus,

$$\begin{aligned} u'(x) &= -\frac{1}{x} \\ v'(x) &= \frac{1}{x^2}. \end{aligned}$$

Thus,  $u(x) = -\ln|x|$  and  $v(x) = -\frac{1}{x}$ . Therefore,

$$y_p = \ln|x|e^{2x} - e^{-2x} \implies \boxed{y = C_1 e^{-2x} + C_2 x e^{-2x} + \ln|x|e^{2x}}.$$

□

**Example 3.3.7** (Undetermined Coefficients)

$$y'' + y' + y = 3x^2 + 4.$$

*Solution.* We first find that

$$y_h = e^{(-1/2)x} \left( C_1 \cos(\sqrt{3}x/2) + C_2 \sin(\sqrt{3}x/2) \right).$$

Then we let  $y_p = D_1x^2 + D_2x + D_3$ . Therefore

$$\begin{aligned} 2D_1 + 2xD_1 + D_2 + D_1x^2 + D_2x + D_3 &= 3x^2 + 4 \\ x^2(D_1) + x(2D_1 + D_2) + (2D_1 + D_2 + D_3) &= 3x^2 + 4. \end{aligned}$$

Solving the resulting system yields  $D_1 = 3, D_2 = -6, D_3 = 4$ . Therefore

$$y_p = 3x^2 - 6x + 4.$$

So,

$$y = e^{(-1/2)x} \left( C_1 \cos(\sqrt{3}x/2) + C_2 \sin(\sqrt{3}x/2) \right) + 3x^2 - 6x + 4.$$

□

**Example 3.3.8** (Variation of parameters)

$$y'' + 4y = \tan x.$$

*Solution.* We first find  $y_h = C_1 \cos(2x) + C_2 \sin(2x)$ . Now, we notice that wronskian is

$$w = \det \left( \begin{bmatrix} \cos(2x) & \sin(2x) \\ -2\sin(2x) & 2\cos(2x) \end{bmatrix} \right) = 2.$$

Thus,

$$u'(x) = -\frac{\tan x \sin(2x)}{2} = -\sin^2(x)$$

and

$$v'(x) = \frac{1}{2} \ln |\cos x| - \frac{\cos(2x)}{4} = \frac{\sin(2x)}{2} - \frac{1}{2} \tan x.$$

Solving, we find  $u(x) = \frac{\sin(2x)}{4} - \frac{1}{2}x$ .  $v(x) = \frac{1}{2} \ln |\cos x| - \frac{\cos 2x}{4}$ . Thus,

$$y_p = -\frac{1}{2} \cos(2x) + \frac{1}{2} \sin(2x) \ln |\cos x|.$$

So,

$$y = C_1 \cos(2x) + C_2 \sin(2x) - \frac{1}{2} \cos(2x) + \frac{1}{2} \sin(2x) \ln |\cos x|$$

□

**Exercise 3.3.9.** Find  $y$  for the differential equation  $y'' + 3y' + 2y = \frac{1}{1+e^x}$ .

### §3.4 Ordinary Differential Equations with Variable Coefficients

**Euler's Equation** is the following

$$a_n x^n y^{(n)} + a_{n-1} x^{n-1} y^{(n-1)} + \cdots + a_1 x y' + a_0 y = f(x).$$

The methods for solving these differential equations are the **transformation method**, which changes to an equation with constant coefficients, and the **direct method**.

#### Theorem 3.4.1 (Transformation Method)

Let  $x = e^z$ . Plugging in  $e^z$  into  $y(x)$ , we get  $\hat{y}(z)$ . Thus,

$$y' = \frac{dy}{dx} = \frac{d\hat{y}}{dz} \frac{dz}{dx} = \hat{y}' \frac{dz}{dx} = \hat{y}' \frac{1}{x}.$$

Then,  $y''$  follows to be

$$y'' = \frac{\hat{y}'' - \hat{y}'}{x^2}.$$

**Exercise 3.4.2.** Find  $y'''$ .

#### Example 3.4.3 (Transformation Method)

We seek to solve the differential equation

$$x^2 y'' - x y' + y = 0.$$

Using the transformation method, we get

$$x^2 \left( \frac{\hat{y}'' - \hat{y}'}{x^2} \right) - x \left( \frac{\hat{y}'}{x} \right) + \hat{y} = 0.$$

Simplifying gives

$$\hat{y}'' - 2\hat{y}' + \hat{y} = 0.$$

This is now a differential equation with constant coefficients, which we know how to solve easily. Thus, we let  $\hat{y} = e^{mz}$ . Then,  $\hat{y}_h = Ae^z + Be^z$ . Putting everything in  $x$ , we get

$$y_h = Ax + Bx \ln x.$$

#### Theorem 3.4.4 (Direct Method)

Assume  $y = x^m$ , where  $m \in \mathbb{C}$ .



**Example 3.4.5 (Direct Method)**

We seek to solve the differential equation

$$x^2 y'' - xy' + y = 0.$$

Letting  $y = x^m$ , we have  $y' = mx^{m-1}$  and  $y'' = m(m-1)x^{m-2}$ . Plugging in, we get  $x^m (m^2 - 2m + 1) = 0$ . Therefore,  $m = 1$ , meaning that  $y_1 = C_1 x$ . We now proceed to use reduction of order. Thus,  $y_2 = f(x)y_1$ . So,

$$\begin{aligned} y_2' &= f'y_1 + fy_1' = f'x + f \\ y_2'' &= f''y_1 + 2f'y_1' + y_1'' = f''x + 2f'. \end{aligned}$$

Plugging this back into the original differential equation, we get

$$x^2 (xf''(x) + 2f'(x)) - x(xf'(x) + f(x)) + xf(x) = 0.$$

Simplifying and rearranging, we get

$$x^3 f''(x) + x^2 f'(x) = 0.$$

Letting  $g(x) = f'(x)$ , we obtain the following separable differential equation

$$\frac{1}{g} \frac{dg}{dx} = -\frac{1}{x} \implies g(x) = \frac{1}{x}.$$

Thus,  $f(x) = \ln x$ . Finally,  $y_2 = x \ln x$  and

$$y_h = Ax + Bx \ln x.$$

**Exercise 3.4.6.** Solve the differential equation  $x^3 y''' + 2x^2 y'' + xy' - y = 0$ .

**Example 3.4.7 (Nonhomogeneous Euler's)**

We seek to solve the differential equation

$$x^2 y'' - xy' + y = x^5.$$

Using the transformation method, we get

$$\hat{y}'' - 2\hat{y}' + \hat{y} = e^{5z}.$$

Now, we can simply use undetermined coefficients. Solving for the homogeneous solution, we get  $\hat{y}_h = Ae^z + Be^z$ . Then, we get  $\hat{y}_p = \frac{1}{16}e^{5z}$ . So,  $y_h = Ax + Bx \ln x$  and  $y_p = \frac{1}{16}x^5$ . Finally,

$$y = Ax + Bx \ln x + \frac{1}{16}x^5.$$

**Exercise 3.4.8.** Solve the differential equation  $x^2 y'' + 3xy' + y = \frac{1}{x(\ln x)^2}$ . Hint: use variation of parameters.

### §3.5 System of Linear ODEs

An example of a system of linear odes is a spring system in series. Our first goal is to change the system that can be written as

$$\begin{bmatrix} y_1' \\ y_2' \end{bmatrix} = \mathbf{A} \begin{bmatrix} y_1 \\ y_2 \end{bmatrix},$$

where  $\mathbf{A}$  is a square matrix. Now, assume,  $y = [C]e^{\lambda x}$  where  $[C]$  and  $\lambda$  are an eigenvalue/vector pair of  $\mathbf{A}$ . Then, the eigenvalues and eigenvectors of  $\mathbf{A}$  form the fundamental solutions

$$y_h = \alpha_1 c_1 e^{\lambda_1 x} + \alpha_2 c_2 e^{\lambda_2 x}.$$

#### Example 3.5.1

We seek to solve the following system of differential equations.

$$\begin{aligned} y_1' + 2y_1 + y_2' + 6y_2 &= 0 \\ 2y_1' + 3y_1 + 3y_2' + 8y_2 &= 0, \end{aligned}$$

where

$$y(0) = \begin{bmatrix} 1 \\ 0 \end{bmatrix}.$$

First, we isolate  $y_1'$  from the first equation to obtain

$$y_1' = -2y_1 - y_2' - 6y_2.$$

Then, plugging this into the second equation and simplifying, we find

$$y_2' = 4y_2 + y_1.$$

$y_1'$  follows to be

$$y_1' = -10y_2 - 3y_1.$$

Thus,

$$\begin{bmatrix} y_1' \\ y_2' \end{bmatrix} = \begin{bmatrix} -3 & -10 \\ 1 & 4 \end{bmatrix} \begin{bmatrix} y_1 \\ y_2 \end{bmatrix}.$$

The eigenvalues and eigenvectors of  $\mathbf{A}$  are

$$\lambda_1 = -1, \lambda_2 = 2, \mathbf{E}_1 = \begin{bmatrix} -5 \\ 1 \end{bmatrix}, \mathbf{E}_2 = \begin{bmatrix} -2 \\ 1 \end{bmatrix}.$$

Therefore,

$$y_h = \alpha_1 \begin{bmatrix} -5 \\ 1 \end{bmatrix} e^{-x} + \alpha_2 \begin{bmatrix} -2 \\ 1 \end{bmatrix} e^{2x}.$$

Solving for  $\alpha_1$  and  $\alpha_2$ , we get  $\alpha_1 = -\frac{1}{3}$  and  $\alpha_2 = \frac{1}{3}$ . Finally,

$$y_h = -\frac{1}{3} \begin{bmatrix} -5 \\ 1 \end{bmatrix} e^{-x} + \frac{1}{3} \begin{bmatrix} -2 \\ 1 \end{bmatrix} e^{2x}.$$

**Exercise 3.5.2.** Solve the following system of linear odes:

$$y' = \begin{bmatrix} 0 & 1 \\ -4 & 0 \end{bmatrix} y; \quad y(0) = \begin{bmatrix} 0 \\ 1 \end{bmatrix}.$$

**Example 3.5.3** (Repeated Roots with a basis)

We seek to solve the following system of differential equations

$$y' = \begin{bmatrix} 1 & -2 & 2 \\ -2 & 1 & -2 \\ 2 & -2 & 1 \end{bmatrix} y; \quad y(0) = \begin{bmatrix} 1 \\ 0 \\ 0 \end{bmatrix}.$$

The eigenvalues for  $\mathbf{A}$  are

$$\lambda_{1/2} = -1, \quad \lambda_3 = 5.$$

The eigenvectors for  $\mathbf{A}$  are

$$\mathbf{E}_1 = \begin{bmatrix} 1 \\ 1 \\ 0 \end{bmatrix}, \quad \mathbf{E}_2 = \begin{bmatrix} 0 \\ 1 \\ 1 \end{bmatrix}, \quad \mathbf{E}_3 = \begin{bmatrix} 1 \\ -1 \\ 1 \end{bmatrix}.$$

Therefore,

$$y_h = \alpha_1 \begin{bmatrix} 1 \\ 1 \\ 0 \end{bmatrix} e^{-x} + \alpha_2 \begin{bmatrix} 0 \\ 1 \\ 1 \end{bmatrix} e^{-x} + \alpha_3 \begin{bmatrix} 1 \\ -1 \\ 1 \end{bmatrix} e^{5x}.$$

Solving for the constants, we find

$$y_h = \frac{1}{3} \begin{bmatrix} 2 \\ 1 \\ -1 \end{bmatrix} e^{-x} + \frac{1}{3} \begin{bmatrix} 1 \\ -1 \\ 1 \end{bmatrix} e^{5x}.$$

**Example 3.5.4** (Repeated Roots with no Basis)

We seek to solve the following systems of differentials

$$y' = \begin{bmatrix} 8 & 1 \\ -4 & 4 \end{bmatrix} y; \quad y(0) = \begin{bmatrix} 17 \\ 42 \end{bmatrix}.$$

The eigenvalue of  $\mathbf{A}$  is  $\lambda = 6$ , where the eigenvector is  $\mathbf{C} = \begin{bmatrix} -1 \\ 2 \end{bmatrix}$ . Therefore,

$y_1 = \alpha_1 \begin{bmatrix} -1 \\ 2 \end{bmatrix} e^{6x}$ . Now, we proceed to use a method that is similar to reduction of order. Thus, we let

$$y_2 = \begin{bmatrix} a + bx \\ c + dx \end{bmatrix} e^{6x} \implies y_2' = \begin{bmatrix} b \\ d \end{bmatrix} e^{6x} + \begin{bmatrix} -1 \\ 2 \end{bmatrix} 6e^{6x}$$

Plugging into the original differential equation, we have

$$\begin{bmatrix} b \\ d \end{bmatrix} e^{6x} + \begin{bmatrix} -1 \\ 2 \end{bmatrix} 6e^{6x} = \begin{bmatrix} 8 & 1 \\ -4 & 4 \end{bmatrix} \begin{bmatrix} a + bx \\ c + dx \end{bmatrix} e^{6x}$$

Therefore,

$$\begin{bmatrix} b + 6a \\ d + 6c \end{bmatrix} e^{6x} + \begin{bmatrix} 6b \\ 6d \end{bmatrix} xe^{6x} = \begin{bmatrix} 8a + c \\ -4a + 4c \end{bmatrix} e^{6x} + \begin{bmatrix} 8b + d \\ -4b + 4d \end{bmatrix} xe^{6x}.$$

Solving the system, we have

$$a = -\frac{m+2n}{4} \quad b = -\frac{m}{2} \quad c = n \quad d = m$$

for  $m, n \in \mathbb{R}$ . Letting  $n = 1$  and  $m = -2$ , we get  $a = 0, b = 1, c = 1, d = -2$ . Therefore,

$$y_2 = \alpha_2 \begin{bmatrix} x \\ 1 - 2x \end{bmatrix} e^{6x}.$$

Solving for  $\alpha_1$  and  $\alpha_2$ , we find

$$y = -17 \begin{bmatrix} -1 \\ 2 \end{bmatrix} e^{6x} + 76 \begin{bmatrix} x \\ 1 - 2x \end{bmatrix} e^{6x} \implies y = \begin{bmatrix} 17 \\ 42 \end{bmatrix} e^{6x} + 76 \begin{bmatrix} 1 \\ -2 \end{bmatrix} xe^{6x}.$$

**Exercise 3.5.5** (Undetermined Coefficients). Solve the following system of differential equations:

$$y' = \begin{bmatrix} 1 & 2 \\ -1 & 4 \end{bmatrix} y + \begin{bmatrix} 1+x \\ e^x \end{bmatrix}.$$

*Solution.* The homogeneous solution is

$$y_h = \alpha_1 \begin{bmatrix} 2 \\ 1 \end{bmatrix} + \alpha_2 \begin{bmatrix} 1 \\ 1 \end{bmatrix} e^{3x}.$$

The particular solution is

$$y_p = \begin{bmatrix} d_1 \\ d_2 \end{bmatrix} e^x + \begin{bmatrix} r_1 \\ r_2 \end{bmatrix} x + \begin{bmatrix} s_1 \\ s_2 \end{bmatrix}.$$

Plugging into the original differential equation, we obtain

$$\begin{aligned} \begin{bmatrix} d_1 \\ d_2 \end{bmatrix} e^x + \begin{bmatrix} r_1 \\ r_2 \end{bmatrix} x &= \begin{bmatrix} 1 & 2 \\ -1 & 4 \end{bmatrix} \left( \begin{bmatrix} d_1 \\ d_2 \end{bmatrix} e^x + \begin{bmatrix} r_1 \\ r_2 \end{bmatrix} x + \begin{bmatrix} s_1 \\ s_2 \end{bmatrix} \right) + \begin{bmatrix} 1+x \\ e^x \end{bmatrix} \\ \begin{bmatrix} d_1 \\ d_2 \end{bmatrix} e^x + \begin{bmatrix} r_1 \\ r_2 \end{bmatrix} x &= \begin{bmatrix} d_1 + d_2 \\ -d_1 + 4d_2 + 1 \end{bmatrix} e^x + \begin{bmatrix} r_1 + 2r_2 + 1 \\ -r_1 + 4r_2 \end{bmatrix} x + \begin{bmatrix} s_1 + 2s_2 + 1 \\ -s_1 + 4s_2 \end{bmatrix}. \end{aligned}$$

Comparing coefficients, we find that

$$\begin{aligned} d_1 &= 1 & d_2 &= 0 \\ r_1 &= -2/3 & r_2 &= -1/6 \\ s_1 &= 19/18 & s_2 &= -11/36 \end{aligned}$$

Thus

$$y = \alpha_1 \begin{bmatrix} 2 \\ 1 \end{bmatrix} e^x + \alpha_2 \begin{bmatrix} 1 \\ 1 \end{bmatrix} e^{3x} + \begin{bmatrix} 1 \\ 0 \end{bmatrix} e^x + \begin{bmatrix} -2/3 \\ -1/6 \end{bmatrix} x + \begin{bmatrix} 19/18 \\ -11/36 \end{bmatrix}.$$

□

We now proceed to examine the method of variation of parameters in solving systems of differential equations. Suppose we have the following system:

$$y' = \mathbf{A}y + f.$$

Let the  $y_1, y_2, \dots, y_n$  be the fundamental solutions of the system and

$$\mathbf{Y} = \begin{bmatrix} y_1 & y_2 & \cdots & y_n \end{bmatrix}.$$

Then we have

$$y_p = \mathbf{Y} \int \mathbf{Y}^{-1} f \, dx.$$

**Example 3.5.6** (Variation of Parameters)

Solve the following system of differential equations:

$$y' = \begin{bmatrix} 1 & 3 \\ 3 & 1 \end{bmatrix} y + \begin{bmatrix} 3 \\ -3 \end{bmatrix} \sqrt{t} e^{-2t}.$$

Solving for the homogeneous portion, we have

$$y_h = \alpha_1 \begin{bmatrix} 1 \\ 1 \end{bmatrix} e^{4x} + \alpha_2 \begin{bmatrix} 1 \\ -1 \end{bmatrix} e^{-2x}.$$

So, we let

$$\mathbf{Y} = \begin{bmatrix} e^{4x} & e^{-2x} \\ e^{4x} & e^{-2x} \end{bmatrix}.$$

The inverse of  $\mathbf{Y}$  is

$$\mathbf{Y}^{-1} = \frac{1}{-2e^{2x}} \begin{bmatrix} -e^{-2x} & -e^{-2x} \\ -e^{4x} & e^{4x} \end{bmatrix} = \frac{1}{2} \begin{bmatrix} e^{-4x} & e^{-4x} \\ e^{2x} & -e^{2x} \end{bmatrix}$$

From this

$$\mathbf{Y}^{-1} f = \begin{bmatrix} 0 \\ 3\sqrt{t} \end{bmatrix}.$$

Thus,

$$\int \mathbf{Y}^{-1} f \, dt = \int \begin{bmatrix} 0 \\ 3\sqrt{t} \end{bmatrix} dt = \begin{bmatrix} 0 \\ 2t^{3/2} \end{bmatrix}.$$

So,

$$\mathbf{Y} \int \mathbf{Y}^{-1} f \, dt = \begin{bmatrix} 2t^{3/2} e^{-2t} \\ -2t^{3/2} e^{-2t} \end{bmatrix}.$$

Our general solution is therefore,

$$y = \alpha_1 \begin{bmatrix} 1 \\ 1 \end{bmatrix} e^{4x} + \alpha_2 \begin{bmatrix} 1 \\ -1 \end{bmatrix} e^{-2x} + \begin{bmatrix} 1 \\ -1 \end{bmatrix} 2t^{3/2} e^{-2t}.$$

### §3.6 Power Series Approach

Sometimes an ordinary differential equation is not solvable using the standard methods introduced thus far. Therefore, using a power series as a guess for the general solution can be a powerful approach. To examine this, we take a look at an example that may also be solved using a separation of variables.

#### Example 3.6.1 (Power Series)

Solve for  $y$ :

$$(x - 3)y' + 2y = 0.$$

*Solution.* The guess we make for the general solution of  $y$  is

$$y = a_0x^0 + a_1x^1 + a_2x^2 + \cdots = \sum_{n=0}^{\infty} a_nx^n.$$

Taking the derivative of this, we get

$$y' = a_1 + 2a_2x + 3a_3x^2 + \cdots = \sum_{n=1}^{\infty} a_nnx^{n-1}.$$

Plugging in this into our differential equation, we obtain

$$\begin{aligned} (x - 3) \sum_{n=1}^{\infty} a_nnx^{n-1} + 2 \sum_{n=0}^{\infty} a_nx^n &= 0 \\ x \sum_{n=1}^{\infty} a_nnx^{n-1} - 3 \sum_{n=1}^{\infty} a_nnx^{n-1} + 2 \sum_{n=0}^{\infty} a_nx^n &= 0 \\ \sum_{n=1}^{\infty} a_nnx^n - 3 \sum_{n=1}^{\infty} a_nnx^{n-1} + 2 \sum_{n=0}^{\infty} a_nx^n &= 0 \end{aligned}$$

Now, we seek to obtain the same exponent on  $x$  for each summation so that it becomes easier to combine each sum. Therefore, we perform a **change of indices** on the middle term, letting  $n \rightarrow n + 1$ . This gives

$$\begin{aligned} \sum_{n=1}^{\infty} a_nnx^n - 3 \sum_{n=0}^{\infty} a_{n+1}(n+1)x^n + 2 \sum_{n=0}^{\infty} a_nx^n &= 0 \\ \sum_{n=1}^{\infty} a_nnx^n + \sum_{n=0}^{\infty} (2a_n - 3a_{n+1}(n+1))x^n &= 0 \\ \sum_{n=1}^{\infty} a_nnx^n + \sum_{n=1}^{\infty} (2a_n - 3a_{n+1}(n+1))x^n &= 3a_1 - 2a_0 \\ \sum_{n=1}^{\infty} ((n+2)a_n - 3a_{n+1}(n+1))x^n &= 3a_1 - 2a_0. \end{aligned}$$

Comparing coefficients gives  $2a_0 - 3a_1 = 0$  and  $(n+2)a_n - 3a_{n+1}(n+1) = 0$  for all  $n \geq 1$ . Thus, we have the following recursion

$$a_{n+1} = \frac{(n+2)a_n}{3(n+1)},$$

where  $a_1 = (2/3)a_0$ . We try now to find a closed form for  $a_n$ . This is usually done by finding a pattern among the terms. Thus, listing out the first few terms, we have

$n$	$a_n$
0	$a_0$
1	$(2/3)a_0$
2	hi
3	hi
4	hi
5	hi

$$\begin{aligned}
 a_1 &= \frac{2}{3}a_0 \\
 a_2 &= \frac{1}{3}a_0 \\
 a_3 &= \frac{4}{3^3}a_0 \\
 a_4 &= \frac{5}{3^4}a_0 \\
 a_5 &= \frac{6}{3^5}a_0.
 \end{aligned}$$

Therefore, the closed form is most likely

$$a_n = \frac{n+1}{3^n}a_0.$$

So, we have

$$\begin{aligned}
 y &= a_0 \sum_{n \geq 0} \frac{n+1}{3^n} x^n \\
 &= a_0 \sum_{n \geq 0} n \left(\frac{x}{3}\right)^n + a_0 \sum_{n \geq 0} \left(\frac{x}{3}\right)^n \\
 &= a_0 \left( \frac{x/3}{(1 - (x/3))^2} + \frac{1}{1 - (x/3)} \right) \\
 &= \frac{a_0}{(1 - (x/3))^2}.
 \end{aligned}$$

□

### Theorem 3.6.2 (Frobenius Method)

In the case we are faced with the differential equation

$$y'' + p(x)y' + q(x)y = 0,$$

where  $p(x)$  and  $q(x)$  are of the form  $b(x)/x$  and  $c(x)/x^2$ , respectively, the initial guess for  $y$  is

$$x^r \sum_{n \geq 0} a_n x^n.$$

The value of  $r$  is determined by the indicial equation  $r(r-1) + rb_0 + c_0 = 0$ . For the multiple  $r$  values found, use the bigger value of  $r$ . This method produces one fundamental solution. The other solution is found with a reduction of order, where  $y_2 = u(x)y_1(x)$  such that

$$u'(x) = \frac{1}{y^2} e^{-\int p(x) dx}.$$



**Example 3.6.3**

We desire to solve the following differential equation

$$xy'' + 2y' + 4xy = 0.$$

Re-expressing the differential equation, we have

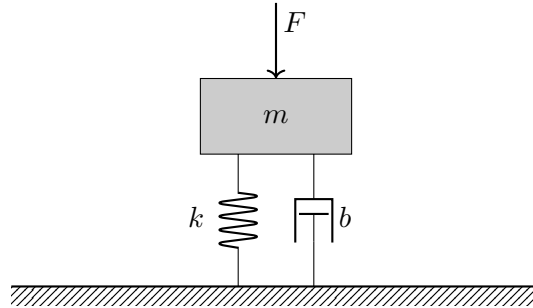
$$y'' + \frac{2}{x}y' + \frac{4x^2}{x^2}y = 0.$$



# 4 Applications of Mathematical Methods

## §4.1 Fundamentals of Translational and Rotational Systems

Damper systems do not have equilibrium but spring systems do. The number of odes needed to be solved is based on the number of degrees of freedom in the system.



A **stiffness element** is a spring as shown below. A spring with an unstretched length of  $l_0$  has a length of

$$l(t) = l_0 + x_2(t) - x_1(t)$$

with the application of the shown forces in the figure below. For a linear spring  $F = k(x_2 - x_1)$ , where  $k$  is the **stiffness coefficient**. Simplifying this gives  $F = kx(t)$  or just  $F = kx$ .

