

ORDINARY DIFFERENTIAL EQUATIONS

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Chapter 1

AN INTRODUCTION

1.1 The Wave Equation

January 5th.

The story of ordinary differential equations (ODEs) begins with Newton in the 17th century, where he laid the foundations of classical mechanics and formulated the laws of motion. During this time, he also (co)developed calculus, which provided the mathematical framework necessary to describe change and motion. Thus came about the first ordinary differential equations, which were used to model the motion of moving bodies.

Around the mid-18th century, questions were asked regarding the vibration of strings. Let us focus on such a string of length L fixed at both ends, and place a coordinate system from 0 to L along the string. At a time t , the string may be displaced from its equilibrium position by a small amount $u(x, t)$ at a point x along the string. We wish to understand this $u(x, t)$.

Consider a small segment of the string between x and $x + \Delta x$. The tension in the string at x is given by $T(x, t)$, and at $x + \Delta x$ it is given by $T(x + \Delta x, t)$. The vertical components of these tensions are $V(x, t) = T(x, t) \sin \theta$ and $V(x + \Delta x, t) = T(x + \Delta x, t) \sin(\theta + \Delta \theta)$ respectively, where θ is the angle the string makes with the horizontal axis at point x . Thus, using Newton's second law, the net vertical force on the segment is given by

$$V(x + \Delta x, t) - V(x, t) = \rho \Delta x u_{tt}(\bar{x}, t), \quad (1.1)$$

where ρ is the linear mass density of the string. Dividing by Δx and taking the limit as $\Delta x \rightarrow 0$, we obtain

$$\partial_x V(x, t) = \rho u_{tt}(x, t). \quad (1.2)$$

The horizontal components of the tension must balance out giving us $H(x, t) = H(x + \Delta x, t)$, where $H(x, t) = T(x, t) \cos \theta$ and $H(x + \Delta x, t) = T(x + \Delta x, t) \cos(\theta + \Delta \theta)$. Since $V(x, t) = H(x, t) \tan \theta$ and $\tan \theta$ can be approximated as

$$\tan \theta \approx \frac{u(x + \Delta x, t) - u(x, t)}{\Delta x} = \partial_x u(x, t), \quad (1.3)$$

we have

$$V(x, t) = \partial_x u(x, t) H(x, t) = H_0 \partial_x u(x, t). \quad (1.4)$$

Plugging this in to the earlier equation, we get

$$\partial_x (H_0 \partial_x u(x, t)) = \rho u_{tt}(x, t) \implies \frac{H_0}{\rho} u_{xx}(x, t) = u_{tt}(x, t). \quad (1.5)$$

This is known as the wave equation, and it models the vibrations of the string. We drop the constants for now; we wish to now solve $u_{xx} = u_{tt}$ with boundary conditions $u(0, t) = 0$ and $u(L, t) = 0$ for all $t \geq 0$, and initial conditions $u(x, 0) = f(x)$ and $u_t(x, 0) = 0$ for all $x \in [0, L]$.

We make the assumption that $u(x, t) = v(x)w(t)$, that the variables can be separated. Plugging this in, we get $u_{tt}(x, t) = v(x)w''(t)$ and $u_{xx}(x, t) = v''(x)w(t)$. Thus,

$$v''(x)w(t) = v(x)w''(t) \implies \frac{v''(x)}{v(x)} = \frac{w''(t)}{w(t)}. \quad (1.6)$$

Since the variables are independent on both sides, this ratio must be a constant $\lambda \in \mathbb{R}$. We look at functions that satisfy $v''(x) = \lambda v(x)$. If $\lambda > 0$, then functions of the form $v(x) = Ae^{\sqrt{\lambda}x} + Be^{-\sqrt{\lambda}x}$ satisfy the equation. $\lambda = 0$ gives functions of the form $v(x) = Ax + B$ and $\lambda < 0$ gives functions of the form $v(x) = A \sin(\sqrt{-\lambda}x) + B \cos(\sqrt{-\lambda}x)$. Let us say $\lambda = -1$. Let us show that the only solutions of $v'' + v = 0$ are of this form $A \sin x + B \cos x$ for some $A, B \in \mathbb{R}$.

Suppose g is a solution of $v'' + v = 0$. Let's assume that $g(0) = B$ and $g'(0) = A$. Consider the function $h(x) = g(x) - (A \sin x + B \cos x)$. We have $h(0) = 0$ and $h'(0) = 0$. Also, $h''(x) + h(x) = 0$. Define $\Psi = (h')^2 + h^2$. This gives

$$\Psi' = 2h'h'' + 2hh' = 2h'(h'' + h) = 0. \quad (1.7)$$

Thus, Ψ is constant. Since $\Psi(0) = (h'(0))^2 + (h(0))^2 = 0$, we have $\Psi(x) = 0$ for all x which gives $h \equiv 0$; g must be of the form $A \sin x + B \cos x$. The same argument works for all $\lambda < 0$.

If we let $\lambda < 0$, then the boundary conditions become $V(0) = 0$ and $V(L) = 0$. Since V must be of the form $V(x) = A \sin(\sqrt{-\lambda}x) + B \cos(\sqrt{-\lambda}x)$, we have $V(0) = B = 0$. Thus, $V(x) = A \sin(\sqrt{-\lambda}x)$. The second boundary condition gives us $V(L) = A \sin(\sqrt{-\lambda}L) = 0$. For a non-trivial solution, we must have $\sin(\sqrt{-\lambda}L) = 0$, which gives us $\sqrt{-\lambda}L = n\pi$ for some $n \in \mathbb{N}$. Thus, $\lambda = -n^2\pi^2/L^2$. From the same ratio equation, we also obtain

$$w(t) = a \sin\left(\frac{n\pi}{L}t\right) + b \cos\left(\frac{n\pi}{L}t\right). \quad (1.8)$$

The initial condition $w'(0) = 0$ gives us $a = 0$. Having obtained v and w , we found a solution of the wave equation as

$$u_n(x, t) = c_n \sin\left(\frac{n\pi}{L}x\right) \cos\left(\frac{n\pi}{L}t\right). \quad (1.9)$$

Note that if ϕ and ψ are two different solutions of the wave equation, then so is any linear combination of the two. Thus, we can combine all these solutions to get

$$u(x, t) = \sum_{n \geq 1} c_n \sin\left(\frac{n\pi}{L}x\right) \cos\left(\frac{n\pi}{L}t\right). \quad (1.10)$$

It can be shown that the infinite summation above makes sense. In fact, every solution is of this form(!). Assuming this statement, let us use the initial condition $u(x, 0) = f(x)$ to determine the coefficients c_n . We have

$$f(x) = \sum_{n \geq 1} c_n \sin\left(\frac{n\pi}{L}x\right). \quad (1.11)$$

This is known as the Fourier sine series of f . The coefficients can be determined using the orthogonality of the sine functions. Multiplying both sides by $\sin(\frac{m\pi}{L}x)$ and integrating from 0 to L , we get

$$c_m = \frac{2}{L} \int_0^L f(x) \sin\left(\frac{m\pi}{L}x\right) dx. \quad (1.12)$$

A similar approach is used in two dimensions, where instead of a string of length L , there is a drum (membrane) Ω of boundary Γ . Here, the wave equation satisfies $\partial_{tt}u = \Delta u$, where Δ is the Laplacian operator. The boundary conditions are $u(x, t) = 0$ for all $x \in \Gamma$ and $t \geq 0$, and the initial conditions are $u(x, 0) = f(x)$ and $u_t(x, 0) = 0$ for all $x \in \Omega$.

1.1.1 (Ordinary) Differential Equations

A general theme of the subject is that we have a system that evolves with time. The evolution of this function is encoded in differential equations, and vice versa. We wish to understand this evolution, or to

determine solutions of the differential equations; we wish to determine their existence, uniqueness, and even explicit forms. Finally, we also look at how the system and solutions depend on initial conditions.

To put it explicitly, a *differential equation* is of the form $F(t, f', f'', \dots, f^{(n)}) = 0$, where t is an independent variable and f is a function of t .

January 7th.

Note that at the moment, we are not assuming anything about the ‘expression’ function F ; it could be linear or non-linear, explicit or implicit, algebraic or transcendental, continuous or discontinuous, and so on. The highest order of derivative appearing in the expression is called the *order* of the differential equation.

Example 1.1. $y''' + t \sin(y') + y = 0$ is a third-order differential equation. Here, t is the independent variable and y is the dependent variable.

Natural questions arise; does a solution exist? Is it unique? For how long does it exist? How does it depend on initial conditions? We divert our attention first to *first-order differential equations*, i.e., those of the form $F(t, y, y') = 0$.

It may be noted that a solution may not even exist for a given differential equation. A simple example is given by $(y')^2 + 1 = 0$. Thus, a solution need not always exist. Also note that even if a solution exists, it may not be unique. For example, consider the differential equation $(y' - 2)(y' + 2) = 0$; both $y = 2t$ and $y = -2t$ are solutions satisfying the same initial condition $y(0) = 0$. Finally, let us see an example where a solution exists and is unique, but only for a limited time. Consider the differential equation $y' = y^2$ with the initial condition $y(0) = 1$. The solution is given by $y(t) = \frac{1}{1-t}$, which exists and is unique for $t \in (-\infty, 1)$, but blows up as $t \rightarrow 1$.

1.1.2 First-Order ODEs

Let us consider first-order ODEs of the form

$$\dot{y} = f(t, y). \quad (1.13)$$

If we assume that the variables can be separated, that is, $f(t, y) = w(y)v(t)$ for some functions w and v , then we can rewrite this as

$$\frac{1}{w(y)} \dot{y} = v(t) \implies \frac{dy}{w(y)} = v(t) dt. \quad (1.14)$$

If W is an antiderivative of $1/w$, and V is an antiderivative of v , then we have

$$W(y(t)) = V(t) + C, \quad (1.15)$$

for some constant $C \in \mathbb{R}$. This gives us an implicit solution of the differential equation. If W is invertible, then we can make it explicit. Of course, this calculation is completely formal. For a more rigorous treatment,

$$\frac{1}{w(y)} \frac{dy}{dt} = v(t) \implies \frac{d}{dt} W(y(t)) = \frac{d}{dt} V(t) \implies W(y(t)) = V(t) + C. \quad (1.16)$$

This is an algebraic point of view; given $F(t, y, y') = 0$, we solve for y . There is also a geometric point of view. Recall that a *curve* in \mathbb{R}^n is a continuous function $\gamma : [0, 1] \rightarrow \mathbb{R}^n$. If γ is k -times differentiable, then we say that γ is a C^k curve. A *vector field* on $S \subseteq \mathbb{R}^n$ is a function $V : S \rightarrow \mathbb{R}^n$. Again, it is termed continuous or C^k if the function is continuous or k -times differentiable respectively. We may also have a time-dependent vector field $V : S \times [0, \infty) \rightarrow \mathbb{R}^n$. An *integral curve* of a vector field V on S is a curve $\gamma : [0, 1] \rightarrow S$ such that

$$\dot{\gamma}(t) = V(\gamma(t)). \quad (1.17)$$

If V is time-dependent, then the integral curve satisfies

$$\dot{\gamma}(t) = V(\gamma(t), t). \quad (1.18)$$

Thus, given a first-order ODE $\dot{y} = f(t, y)$, we can think of f as a time-dependent vector field on \mathbb{R} , and solutions of the ODE are integral curves of this vector field. We can also define $V(y, t) = (1, f(t, y))$ as a vector field on \mathbb{R}^2 , and solutions of the ODE correspond to integral curves of this vector field, and are of the form $(t, y(t))$. We can impose certain regularity conditions on f to ensure existence and uniqueness of solutions.

- (i) Note that at least continuity of f is required to ensure the existence of a solution; if f is not continuous, like in the case of

$$f(y, t) = \begin{cases} 1 & \text{if } t \in [0, 1], \\ 0 & \text{if } t > 1, \end{cases}, \quad (1.19)$$

then there is no solution of the ODE $\dot{y} = f(t, y)$ with the initial condition $y(0) = 0$.

- (ii) However, continuity alone does not guarantee uniqueness of solutions. For example, consider the ODE $\dot{y} = \sqrt{|y|}$ with the initial condition $y(0) = 0$. Then both $y(t) = 0$ and $y(t) = \mathbf{1}_{[0, \infty)}(t) \frac{t^2}{4}$ are solutions.

Example 1.2. Let us look at the case of a model for population growth of bacteria. Let $P(t)$ be the population at time t . A simple model given by the differential equation

$$\frac{dP}{dt} = aP \left(1 - \frac{P}{N} \right) \quad (1.20)$$

where a and P are appropriate constants. Here, N is the carrying capacity of the environment. When P is small, the population grows approximately exponentially, but as P approaches N , the growth rate slows down and eventually stops when $P = N$. This is known as the logistic growth model. One can easily solve the ODE $\dot{y} = y(1 - y)$ using the method of separation of variables to obtain

$$y(t) = \frac{a_0 e^t}{1 + a_0 e^t}, \quad (1.21)$$

where $a_0 = y(0)/(1 - y(0))$. This solution approaches 1 as $t \rightarrow \infty$, which corresponds to the carrying capacity in the original model. One can also analyze the long-term behaviour, dependence of initial conditions, etc. without explicitly solving the ODE; this is the concern of dynamics, which will be studied towards the end of the course.

1.2 Exact Equations

Consider a first-order ODE of the form

$$M(x, y) + N(x, y) \frac{dy}{dx} = 0, \quad \text{that is, } M(x, y) dx + N(x, y) dy = 0. \quad (1.22)$$

Such an ODE of the form $M dx + N dy = 0$ is said to be *exact* if there exists a function $g(x, y)$ such that $\partial_x g(x, y) = M(x, y)$ and $\partial_y g(x, y) = N(x, y)$. In this case, the solutions of the ODE are given by $g(x, y) = C$ for some constant $C \in \mathbb{R}$. If there does exist such a function g , then we must have

$$\frac{\partial M}{\partial y} = \frac{\partial N}{\partial x}. \quad (1.23)$$

In fact, the converse is also true; if the above holds, then such a function g exists and the equation is exact.

A vector field V on \mathbb{R}^n is termed a *conservative vector field* if there exists a scalar *potential function* $\varphi : \mathbb{R}^n \rightarrow \mathbb{R}$ such that $V = \nabla \varphi$. Thus, a first-order ODE $M dx + N dy = 0$ is exact if and only if the vector field $V(x, y) = (M(x, y), N(x, y))$ is conservative with potential function g .

Review of Multivariate Calculus

January 12th.

Recall that $f : (a, b) \rightarrow \mathbb{R}$ is differentiable at $p \in (a, b)$ if the limit

$$\lim_{h \rightarrow 0} \frac{f(p+h) - f(p)}{h} \quad (1.24)$$

exists; this limit is denoted by $f'(p)$. If we define

$$\epsilon_p(h) := f(p+h) - f(p) - f'(p)h, \quad (1.25)$$

the error term, then we have

$$f(p+h) = f(p) + f'(p)h + \epsilon_p(h). \quad (1.26)$$

Here, $\lim_{h \rightarrow 0} \epsilon_p(h) = 0$. Moreover, $\lim_{h \rightarrow 0} \frac{1}{h} \epsilon_p(h) = 0$, to indicate this, we write $\epsilon_p(h) = o(h)$ as $h \rightarrow 0$. This is known as the little-o notation. Thus, we have

$$f(p+h) = f(p) + f'(p)h + o(h) \quad \text{as } h \rightarrow 0. \quad (1.27)$$

This is the linear approximation of f at p . If f is differentiable at every point of (a, b) , then we say that f is differentiable on (a, b) . If f' is continuous on (a, b) , then we say that f is continuously differentiable on (a, b) , or $f \in C^1(a, b)$. Let's say $f \in C^1(a, b)$, and say the second derivative of f exists at $p \in (a, b)$. Similar to above, one can show that

$$f(p+h) = f(p) + f'(p)h + \frac{f''(p)}{2}h^2 + o(h^2) \quad \text{as } h \rightarrow 0. \quad (1.28)$$

If a function f is infinitely differentiable, that is, all its derivatives exist, then we say that f is a smooth function, or $f \in C^\infty(a, b)$. There is another class of functions known as analytic functions. A function f is said to be analytic at $p \in (a, b)$ if there exists a power series $\sum_{n=0}^{\infty} a_n(x-p)^n$ that converges to $f(x)$ for all x in some neighbourhood of p . If f is analytic at every point of (a, b) , then we say that f is analytic on (a, b) . It can be shown that if f is analytic at p , then f is infinitely differentiable at p , and the coefficients of the power series are given by

$$a_n = \frac{f^{(n)}(p)}{n!}. \quad (1.29)$$

However, the converse is not true; there exist smooth functions that are not analytic. For example, consider the function

$$f(x) = \begin{cases} e^{-1/x} & \text{if } x > 0, \\ 0 & \text{if } x \leq 0. \end{cases} \quad (1.30)$$

Here, 0 is the only problematic point. It can be shown that f is infinitely differentiable at 0, and $f^{(n)}(0) = 0$ for all $n \geq 0$. Thus, the Taylor series of f at 0 is identically 0, which does not converge to $f(x)$ for any $x > 0$. Thus, f is not analytic at 0.

Suppose $f : (a, b) \rightarrow \mathbb{R}$ is analytic. Assume there exists a sequence of distinct points $(x_n)_{n \geq 1} \subseteq (a, b)$ such that $x_n \rightarrow p \in (a, b)$ and $f(x_n) = 0$ for all $n \geq 1$. Then, it can be shown that f is identically 0 in some neighbourhood of p . If f is analytic on the whole interval (a, b) , then f is identically 0 on (a, b) .

Proof. Let $f(x) = \sum_{n \geq 0} a_n(x-p)^n$, and let $N = \min\{n \geq 0 \mid a_n \neq 0\}$. Assume that f is not identically 0; thus N is finite. Thus, f must be of the form

$$f(x) = a_N(x-p)^N + a_{N+1}(x-p)^{N+1} + \cdots = (x-p)^N(a_N + a_{N+1}(x-p) + \cdots). \quad (1.31)$$

Since $a_N \neq 0$, the term in the parentheses is non-zero in some neighbourhood of p . Thus, $f(x) = 0$ implies that $(x-p)^N = 0$, that is, $x = p$. This contradicts the assumption that there exists a sequence of distinct points $(x_n)_{n \geq 1}$ converging to p such that $f(x_n) = 0$ for all $n \geq 1$. ■

Let us now move to higher dimensions. A function $g : \mathbb{R}^2 \rightarrow \mathbb{R}^2$ is said to be differentiable at a point $p = (x_0, y_0)$ if there exists a linear operator $T_p : \mathbb{R}^2 \rightarrow \mathbb{R}^2$ such that

$$\frac{\|g(x_0 + h, y_0 + k) - g(x_0, y_0) - T_p(h, k)\|}{\|(h, k)\|} \rightarrow 0 \quad \text{as } (h, k) \rightarrow (0, 0). \quad (1.32)$$

The linear operator, if it exists, as a matrix is given by

$$T_p = \begin{bmatrix} \partial_x g_1(p) & \partial_y g_1(p) \\ \partial_x g_2(p) & \partial_y g_2(p) \end{bmatrix}, \quad (1.33)$$

where $g = (g_1, g_2)$. Thus, by a similar calculation as before, we have

$$g(x_0 + h, y_0 + k) = g(x_0, y_0) + T_p(h, k) + o(\|(h, k)\|) \quad \text{as } (h, k) \rightarrow (0, 0). \quad (1.34)$$

For a function $f : \mathbb{R}^2 \rightarrow \mathbb{R}$, differentiability at p is defined similarly, and one would have

$$f(x_0 + h, y_0 + k) = f(x_0, y_0) + \partial_x f(p)h + \partial_y f(p)k + o(\|(h, k)\|) \quad \text{as } (h, k) \rightarrow (0, 0). \quad (1.35)$$

Now suppose $\tilde{f} : \mathbb{R}^2 \rightarrow \mathbb{R}^2$ is an affine map defined as

$$\tilde{f}(x, y) = (c_1, c_2) + A(x, y). \quad (1.36)$$

Such a map is invertible if and only if A is invertible. Recall the inverse function theorem; if $f : \mathbb{R}^2 \rightarrow \mathbb{R}^2$ is a C^1 function, and the derivative of f at p , $Df(p)$, is invertible, then there exist neighbourhoods U of p and V of $f(p)$ such that $f : U \rightarrow V$ is a bijection. In such a case, f can be seen as an approximate affine map near p . Also recall the implicit function theorem: let $f : \mathbb{R}^2 \rightarrow \mathbb{R}$ be a C^1 function. Suppose $f(x_0, y_0) = 0$ and $\partial_x f(x_0, y_0) \neq 0$. Then locally at (x_0, y_0) , that is, in an open neighbourhood U of (x_0, y_0) , there is a C^1 function r such that

$$Z_U = \{(x, y) \in U \mid f(x, y) = 0\} = \{(r(t), t) \mid t \in I\}, \quad (1.37)$$

for some open interval I containing y_0 . We are now interested in level sets of C^1 function $f : \mathbb{R}^2 \rightarrow \mathbb{R}$. For any $l \in \mathbb{R}$, the level set of f at l is defined as

$$E_l = \{(x, y) \in \mathbb{R}^2 \mid f(x, y) = l\}. \quad (1.38)$$

For example, level sets of the function $f(x, y) = x^2 + y^2$ are circles centred at the origin. For the function $f(x, y) = x^2 - y^2$, the level sets are hyperbolas. We claim this: suppose f is such that $\nabla f \neq 0$ on \mathbb{R}^2 . Then for any $l \in \mathbb{R}$, the level set E_l is a 1-manifold in \mathbb{R}^2 . A 1-manifold in \mathbb{R}^2 is a set S that locally looks like \mathbb{R} . That is, for every point p in the set, there exists a neighbourhood U of p such that $U \cap S$ is homeomorphic to an open interval in \mathbb{R} . To this claim, assume $l = 0$ (otherwise, we can look at $f - l$). Let $p = (x_0, y_0) \in E_0$. Since $\nabla f(p) \neq 0$, at least one of $\partial_x f(p)$ or $\partial_y f(p)$ is non-zero. Assume $\partial_y f(p) \neq 0$. By the implicit function theorem, there exists a neighbourhood U of p and an open interval I containing y_0 such that

$$U \cap E_0 = \{(r(t), t) \mid t \in I\}, \quad (1.39)$$

for some C^1 function $r : I \rightarrow \mathbb{R}$. The map $\phi : I \rightarrow U \cap E_0$ defined as $\phi(t) = (r(t), t)$ is a homeomorphism, which shows that E_0 is a 1-manifold. The case when $\partial_x f(p) \neq 0$ is similar. Suppose $f : \mathbb{R}^2 \rightarrow \mathbb{R}$ is a C^1 function such that $\nabla f \neq 0$ on \mathbb{R}^2 . Then the gradient vector field $\nabla f(p)$ at a point p is orthogonal to the level set of f passing through p . Let us move back to exact equations.

Back to Exact Equations

Example 1.3. Consider the ODE

$$e^y dx + (xe^y + 2y)dy = 0. \quad (1.40)$$

Verify that this equation is exact. Thus, solutions are given by $g(x, y) = C$ for some constant $C \in \mathbb{R}$,

where

$$g(x, y) = xe^y + y^2. \quad (1.41)$$

The solutions are level curves of g . Note that $\nabla g(x, y) = (e^y, xe^y + 2y)$. Since $e^y > 0$ for all $y \in \mathbb{R}$, we have $\nabla g(x, y) \neq 0$ for all $(x, y) \in \mathbb{R}^2$. Thus, the level sets of g are 1-manifolds in \mathbb{R}^2 .

We wish to show the converse that if $\partial_y M = \partial_x N$, then the equation is exact.

Proof. We wish to find a function g such that $\partial_x g = M$ and $\partial_y g = N$. Suppose we had found such a g . Then, we would have

$$\partial_x g = M \implies g(x, y) = \int_0^x M dx + \psi(y). \quad (1.42)$$

The partial with respect to y gives

$$N(x, y) = \partial_y g(x, y) = \int_0^x \partial_y M dx + \psi'(y). \quad (1.43)$$

Thus, we obtain

$$\psi'(y) = N(x, y) - \int_0^x \partial_y M(s, y) ds. \quad (1.44)$$

Differentiating with respect to x gives $\partial_x N(x, y) - \partial_y M(x, y) = 0$, which holds by assumption. Thus, $\psi'(y)$ is indeed a function of y alone. ■

So far, we have shown that $Mdx + Ndy = 0$ is exact with solution g , if and only if $F = (M, N)$ is a conservative vector field with respect to the potential function g . Moreover, solutions of the exact equation are level sets of g .

1.2.1 Integrating Factors

Look at the equation

$$ydx + (x^2y - x)dy = 0. \quad (1.45)$$

This equation is not exact. However, if we multiply both sides by the integrating factor $\mu(x, y) = 1/x^2$, we get

$$\frac{y}{x^2}dx + \left(y - \frac{1}{x}\right)dy = 0, \quad (1.46)$$

which is exact. Thus, solutions are given by $g(x, y) = C$ for some constant $C \in \mathbb{R}$, $g(x, y) = \frac{y^2}{2} - \frac{y}{x}$. Such a term $\mu(x, y)$ is known as an *integrating factor*.

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