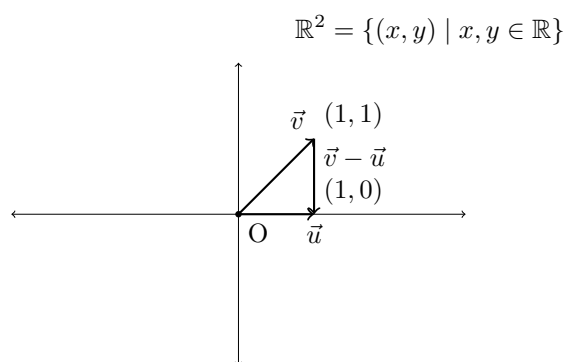


Calculus II

1 Vectors

\mathbb{R} represents the set of real numbers.

\mathbb{R}^2 represents a 2 dimensional real plane.



Normally elements of \mathbb{R} are known as scalars.

- add (or subtract) two vectors
- if $c \in \mathbb{R}$ and $v \in \mathbb{R}^2$, $c\vec{v}$

1.1 Dot Product

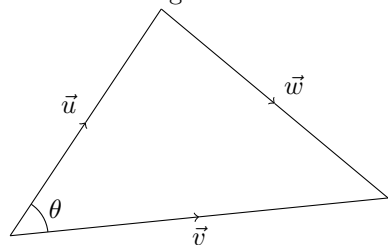
$u = (u_1, u_2)$ and $v = (v_1, v_2)$

$$u.v = u_1.v_1 + u_2.v_2$$

Theorem

$$u.v = |u||v| \cos(\theta)$$

where θ is the angle between \vec{u} and \vec{v} and $|u|$ is the length of vector \vec{u}



Proof:

$$w^2 = u^2 + v^2 - 2|u||v| \cos(\theta) \dots (1)$$

$$\vec{w} = \vec{v} - \vec{u}$$

$$w = (v_1 - u_1, v_2 - u_2)$$

$$w^2 = (v_1 - u_1)^2 + (v_2 - u_2)^2$$

$$w^2 = v_1^2 - 2v_1u_1 + u_1^2 + v_2^2 - 2v_2u_2 + u_2^2$$

$$w^2 = v^2 + u^2 - 2v_1u_1 - 2v_2u_2 \dots (2)$$

now, as (1) = (2)

$$u^2 + v^2 - 2|u||v|\cos(\theta) = v^2 + u^2 - 2v_1u_1 - 2v_2u_2$$

$$|u||v|\cos(\theta) = v_1u_1 + v_2u_2$$

$$|u||v|\cos(\theta) = \vec{u} \cdot \vec{v}$$

Hence proved.

Extending the above theorem to \mathbb{R}^n : Consider $\vec{u} = (u_1, u_2, \dots, u_n), \vec{v} = (v_1, v_2, \dots, v_n) \in \mathbb{R}^n$

$$\vec{u} \cdot \vec{v} = u_1v_1 + u_2v_2 + \dots + u_nv_n$$

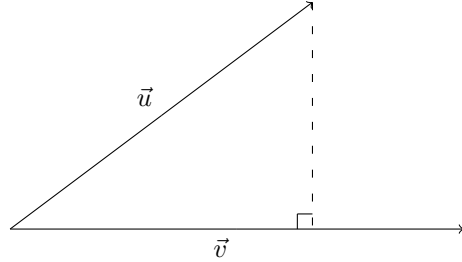
1.2 Unit Vectors

If $\vec{v} \in \mathbb{R}^2$ is a vector. then,

$$\hat{v} = \frac{\vec{v}}{|\vec{v}|}$$

1.3 Projections

If \vec{u} and \vec{v} are vectors in \mathbb{R}^2 and θ is the angle between them:



let \vec{w} be the projection of \vec{u} on \vec{v}

$$\vec{w} = |u|\cos(\theta)\hat{v}$$

$$\vec{w} = \frac{|u|\cos(\theta)|v|\vec{v}}{|v|^2}$$

$$\vec{w} = \frac{\vec{u} \cdot \vec{v}}{|\vec{v}|^2} \vec{v}$$

1.4 Cross Product

Consider the vectors, u, v . Then the cross-product of u and v is defined as:

$$u \times v = |u||v| \sin(\theta) \hat{n}$$

where \hat{n} is the unit vector perpendicular to the plane containing u and v , and also $(\vec{u}, \vec{v}, \hat{n})$ form a right handed system.

Properties of Cross Product:

- $\vec{u} \times \vec{v} = -(\vec{v} \times \vec{u})$
- $(r\vec{u}) \times (s\vec{v}) = rs\vec{u} \times \vec{v}$
- $\vec{u} \times (\vec{v} + \vec{w}) = \vec{u} \times \vec{v} + \vec{u} \times \vec{w}$

\vec{u} and \vec{v} can also be represented as:

$$\vec{u} = u_1 \hat{i} + u_2 \hat{j} + u_3 \hat{k}$$

$$\vec{v} = v_1 \hat{i} + v_2 \hat{j} + v_3 \hat{k}$$

$$\vec{u} \times \vec{v} = (u_2 v_3 - u_3 v_2) \hat{i} + (u_3 v_1 - u_1 v_3) \hat{j} + (u_1 v_2 - u_2 v_1) \hat{k}$$

$$\vec{u} \times \vec{v} = \begin{vmatrix} \hat{i} & \hat{j} & \hat{k} \\ u_1 & u_2 & u_3 \\ v_1 & v_2 & v_3 \end{vmatrix}$$

the above formula is only symbolic and meant to represent a cross product.

2 Multi-Variable Calculus

let $r : \mathbb{R} \rightarrow \mathbb{R}^3$ be a function. (It could be to any \mathbb{R}^n)
for $t \in \mathbb{R}$, $r(t)$ is a vector in \mathbb{R}^3

$$r(t) = f(t)\hat{i} + g(t)\hat{j} + h(t)\hat{k}$$

2.1 Continuity

r is continuous at a if:

$$\lim_{t \rightarrow a} r(t) = r(a)$$

i.e. $\forall \epsilon > 0, \exists \delta > 0$ such that $|t - a| < \delta \implies |r(t) - r(a)| < \epsilon$
or, if f, g and h are continuous at a , r is continuous at a .

2.2 Differentiability

2.3 Integration

let $f : [a, b] \rightarrow \mathbb{R}$ be a function.

the integral of f from a to b is defined as:

$$\int_a^b f(x)dx = \text{Area under the curve } y = f(x) \text{ from } x = a \text{ to } x = b$$

Anti-derivative let $f : [a, b] \rightarrow \mathbb{R}$ be a function.

$$\int f(t)dt = F(t) + c$$

such that $F'(t) = f(t)$ and c is an arbitrary constant

Fundamental Theorem of Calculus let $f : [a, b] \rightarrow \mathbb{R}$ be a function and F be its anti-derivative.

$$\int_a^b f(t)dt = F(b) - F(a)$$

2.3.1 Extending to a Vector Valued Function

Consider a function $r : \mathbb{R} \rightarrow \mathbb{R}^3$ (we are taking \mathbb{R}^3 as an example, it could be any \mathbb{R}^n)

$$\begin{aligned} r(t) &= f(t)\hat{i} + g(t)\hat{j} + h(t)\hat{k} \\ \int_a^b r(t)dt &= \int_a^b f(t)dt\hat{i} + \int_a^b g(t)dt\hat{j} + \int_a^b h(t)dt\hat{k} \end{aligned}$$

Anti-derivative

$$\begin{aligned} \int r(t)dt &= \left(\int f(t)dt + c_1 \right) \hat{i} + \left(\int g(t)dt + c_2 \right) \hat{j} + \left(\int h(t)dt + c_3 \right) \hat{k} \\ \int r(t)dt &= R(t) + C \end{aligned}$$

where $R'(t) = r(t)$ and C is an arbitrary constant vector.

$$R(t) = F(t)\hat{i} + G(t)\hat{j} + H(t)\hat{k}$$

where $F'(t) = f(t)$, $G'(t) = g(t)$ and $H'(t) = h(t)$