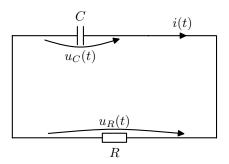


# Beispiel

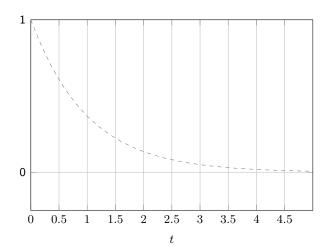


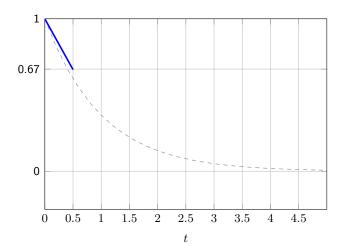
## Beispiel

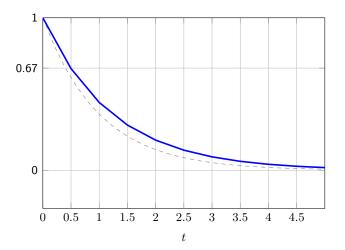
$$\begin{split} u_C(t) &= u_R(t) := u(t) \\ i(t) &= \frac{-u_R(t)}{R} \\ u_C(t) &= u_0 + \frac{1}{C} \int\limits_0^t i(t) \mathrm{d}t \\ \dot{u}(t) &= \frac{-1}{RC} \, u(t), \quad u(0) = u_0 \\ \dot{x} &= \lambda x, \quad x(0) = x_0 \\ \mathrm{hier: } \, \dot{x} &= -x \end{split}$$

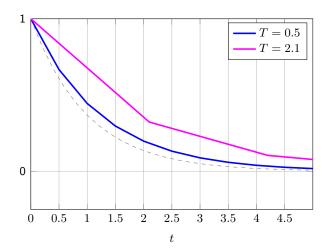
Echte Lösung:

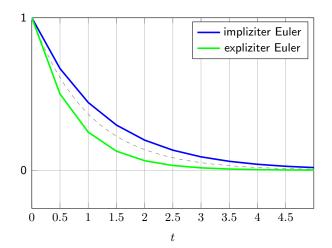
 $-x(t) = x_0 e^{\lambda t}$ 



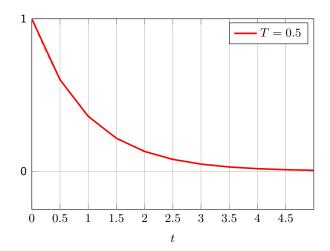




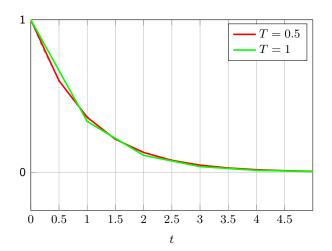




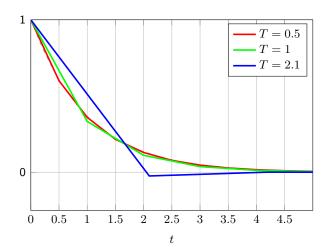
## Trapez



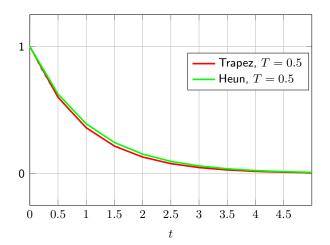
## Trapez



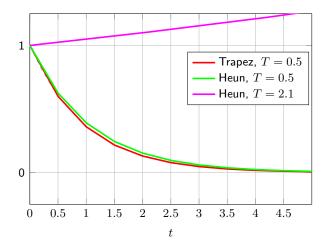
Trapez

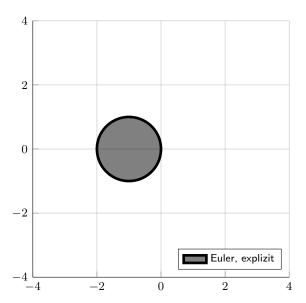


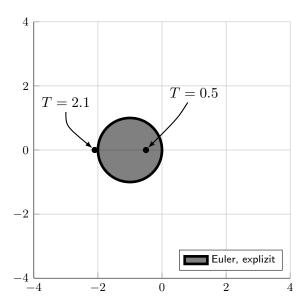
#### Heun

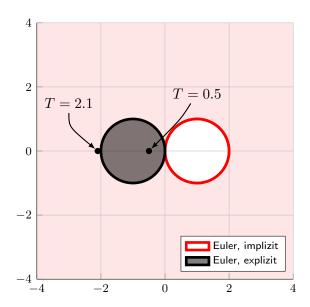


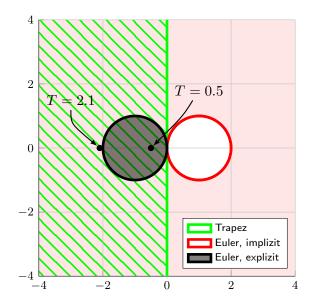
#### Heun

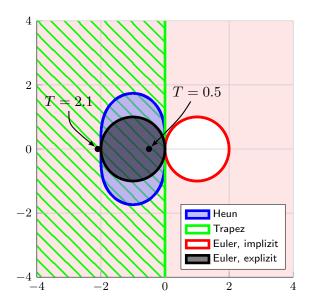












steuerung

hierrein

 $x_{i+1}$  mit Konsistenzordnung s  $\hat{x}_{i+1}$  mit Konsistenzordnung s-1

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