

General coordinates

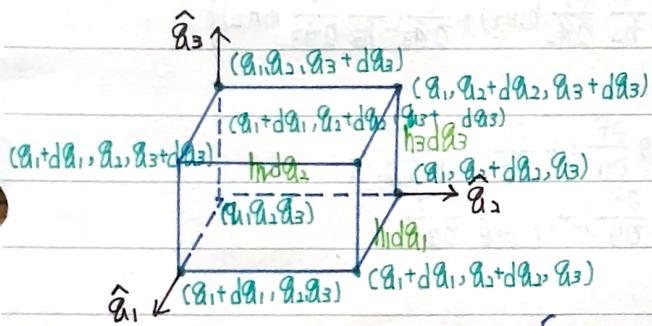
$$d\vec{l} = h_1 d\theta_1 \hat{a}_1 + h_2 d\theta_2 \hat{a}_2 + h_3 d\theta_3 \hat{a}_3$$

	Cartesian	Cylindrical	Spherical
θ_1	x	s	r
θ_2	y	ϕ	θ
θ_3	z	z	ρ
h_1	1	1	1
h_2	1	s	r
h_3	1	1	$r \sin \theta$
\hat{a}_1	\hat{x}	\hat{s}	\hat{r}
\hat{a}_2	\hat{y}	$\hat{\phi}$	$\hat{\theta}$
\hat{a}_3	\hat{z}	\hat{z}	$\hat{\rho}$

$$\begin{aligned}\nabla f &= \frac{\partial f}{\partial \theta_1} \hat{a}_1 + \frac{\partial f}{\partial \theta_2} \hat{a}_2 + \frac{\partial f}{\partial \theta_3} \hat{a}_3 = \frac{\partial f}{h_1 \partial \theta_1} \hat{a}_1 + \frac{\partial f}{h_2 \partial \theta_2} \hat{a}_2 + \frac{\partial f}{h_3 \partial \theta_3} \hat{a}_3 \\ &= \frac{\partial f}{\partial x} \hat{x} + \frac{\partial f}{\partial y} \hat{y} + \frac{\partial f}{\partial z} \hat{z} \\ &= \frac{\partial f}{\partial s} \hat{s} + \frac{1}{s} \frac{\partial f}{\partial \phi} \hat{\phi} + \frac{\partial f}{\partial z} \hat{z} \\ &= \frac{\partial f}{\partial r} \hat{r} + \frac{1}{r} \frac{\partial f}{\partial \theta} \hat{\theta} + \frac{1}{r \sin \theta} \frac{\partial f}{\partial \phi} \hat{\phi}\end{aligned}$$

$$\int_V (\nabla \cdot \vec{B}) d\tau = \oint_S \vec{B} \cdot d\vec{a}$$

$$\nabla \cdot \vec{B} = \lim_{\Delta \tau \rightarrow 0} \frac{\oint_S \vec{B} \cdot d\vec{a}}{\Delta \tau} \quad \vec{B} = B_1 \hat{a}_1 + B_2 \hat{a}_2 + B_3 \hat{a}_3 \quad \Delta \tau = h_1 h_2 h_3 d\theta_1 d\theta_2 d\theta_3$$



$$d\Phi_L = B_2(S_1)(-h_1 d\theta_1 h_3 d\theta_3), \quad d\Phi_R = \left[B_2(S_1) + \frac{\partial B_2}{\partial \theta_2} d\theta_2 \right] (h_1 d\theta_1 h_3 d\theta_3)$$

$$d\Phi_L + d\Phi_R = \frac{\partial B_2}{\partial \theta_2} h_1 h_3 d\theta_1 d\theta_2 d\theta_3$$

$$\text{similarly, } d\Phi = d\theta_1 d\theta_2 d\theta_3 \left[\frac{\partial (B_1 h_2 h_3)}{\partial \theta_1} + \frac{\partial (B_2 h_1 h_2)}{\partial \theta_2} + \frac{\partial (B_3 h_1 h_2)}{\partial \theta_3} \right]$$

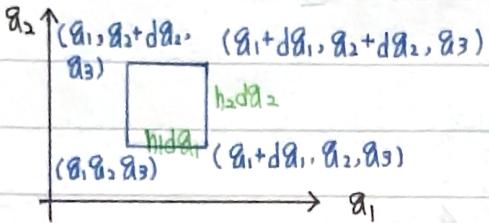
$$\frac{d\Phi}{d\tau} = \nabla \cdot \vec{B} = \frac{1}{h_1 h_2 h_3} \left[\frac{\partial (B_1 h_2 h_3)}{\partial \theta_1} + \frac{\partial (B_2 h_1 h_2)}{\partial \theta_2} - \frac{\partial (B_3 h_1 h_2)}{\partial \theta_3} \right]$$

$$= \frac{\partial B_x}{\partial x} + \frac{\partial B_y}{\partial y} + \frac{\partial B_z}{\partial z}$$

$$= \frac{1}{s} \left(\frac{\partial B_z s}{\partial s} + \frac{\partial B_\phi}{\partial \phi} + \frac{\partial B_z}{\partial z} \right) = \frac{1}{s} \frac{\partial (s B_z)}{\partial s} + \frac{1}{s} \frac{\partial B_\phi}{\partial \phi} + \frac{\partial B_z}{\partial z}$$

$$= \frac{1}{r^2 \sin \theta} \left[\frac{\partial}{\partial r} (B_r \cdot r^2 \sin \theta) + \frac{\partial}{\partial \theta} (B_\theta \cdot r \sin \theta) + \frac{\partial}{\partial \phi} (B_\phi \cdot r) \right] = \frac{1}{r^2} \frac{\partial}{\partial r} (r^2 B_r) + \frac{1}{r \sin \theta} \frac{\partial}{\partial \theta} (\sin \theta B_\theta) + \frac{1}{r \sin \theta} \frac{\partial B_\phi}{\partial \phi}$$

$$\int (\nabla \times \vec{B}) \cdot d\vec{\alpha} = \oint \vec{B} \cdot d\vec{\ell}$$



$$\oint \vec{B} \cdot d\vec{\ell} = B_{1,1} h_1 d\vec{q}_1 + B_{2,2} h_2 d\vec{q}_2 - B_{1,3} h_1 d\vec{q}_1 - B_{2,4} h_2 d\vec{q}_2$$

$$= (B_{1,1} - B_{1,3}) h_1 d\vec{q}_1 + (B_{2,2} - B_{2,4}) h_2 d\vec{q}_2 \quad B_{1,3} = B_{1,1} + \frac{\partial B_1}{\partial q_2} d\vec{q}_2$$

$$= -\frac{\partial B_1}{\partial q_2} h_1 d\vec{q}_1 d\vec{q}_2 + \frac{\partial B_2}{\partial q_1} h_2 d\vec{q}_1 d\vec{q}_2$$

$$= \frac{1}{h_1 h_2} \left(\frac{\partial B_2 h_2}{\partial q_1} - \frac{\partial h_1 B_1}{\partial q_2} \right) \hat{q}_3 \cdot d\vec{\alpha} \quad h_1 h_2 d\vec{q}_1 d\vec{q}_2 \hat{q}_3$$

$$\nabla \times \vec{B} = \frac{1}{h_1 h_2 h_3} \begin{vmatrix} h_1 \hat{q}_1 & h_2 \hat{q}_2 & h_3 \hat{q}_3 \\ \frac{\partial}{\partial q_1} & \frac{\partial}{\partial q_2} & \frac{\partial}{\partial q_3} \\ h_1 B_1 & h_2 B_2 & h_3 B_3 \end{vmatrix}$$

$$= \frac{1}{h_1 h_3} \left(\frac{\partial h_3 B_3}{\partial q_2} - \frac{\partial h_2 B_2}{\partial q_3} \right) \hat{q}_1 + \frac{1}{h_1 h_3} \left(\frac{\partial h_1 B_1}{\partial q_3} - \frac{\partial h_3 B_3}{\partial q_1} \right) \hat{q}_2 + \frac{1}{h_1 h_2} \left(\frac{\partial h_2 B_2}{\partial q_1} - \frac{\partial h_1 B_1}{\partial q_2} \right) \hat{q}_3$$

Laplacian

$$\nabla f = \frac{1}{h_1} \frac{\partial f}{\partial q_1} \hat{q}_1 + \frac{1}{h_2} \frac{\partial f}{\partial q_2} \hat{q}_2 + \frac{1}{h_3} \frac{\partial f}{\partial q_3} \hat{q}_3$$

$$\nabla^2 f = \frac{1}{h_1 h_2 h_3} \left[\frac{\partial}{\partial q_1} \left(\frac{1}{h_1} \frac{\partial f}{\partial q_1} h_2 h_3 \right) + \frac{\partial}{\partial q_2} \left(\frac{1}{h_2} \frac{\partial f}{\partial q_2} h_1 h_3 \right) + \frac{\partial}{\partial q_3} \left(\frac{1}{h_3} \frac{\partial f}{\partial q_3} h_1 h_2 \right) \right]$$

$$= \frac{1}{S} \left(\frac{\partial}{\partial S} S \frac{\partial f}{\partial S} + \frac{1}{S^2} \frac{\partial^2 f}{\partial \phi^2} + \frac{\partial^2 f}{\partial z^2} \right)$$

$$= \frac{1}{r^2 \sin \theta} \left[\frac{\partial}{\partial r} (r^2 \sin \theta \frac{\partial f}{\partial r}) + \frac{\partial}{\partial \theta} (\sin \theta \frac{\partial f}{\partial \theta}) + \frac{\partial}{\partial \phi} \left(\frac{1}{\sin \theta} \frac{\partial f}{\partial \phi} \right) \right]$$

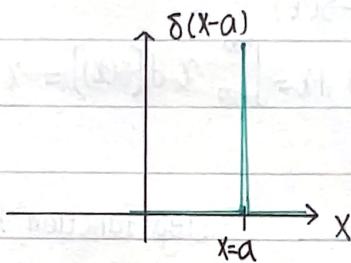
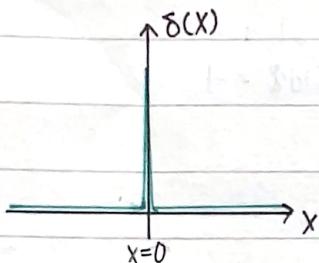
$$= \frac{1}{r^2} \frac{\partial}{\partial r} (r^2 \frac{\partial f}{\partial r}) + \frac{1}{r^2 \sin \theta} \frac{\partial}{\partial \theta} (\sin \theta \frac{\partial f}{\partial \theta}) + \frac{1}{r^2 \sin^2 \theta} \frac{\partial^2 f}{\partial \phi^2}$$

The Dirac Delta Function

consider the vector function $\vec{v} = \frac{1}{r^2} \hat{r}$

$$\nabla \cdot \vec{v} = \frac{1}{r^2 \sin\theta} \frac{\partial}{\partial r} (\frac{1}{r^2} r^2 \sin\theta) = 0 \quad \text{zero everywhere except origin}$$

$$\begin{aligned} \oint_S \vec{v} \cdot d\vec{a} &= \int (\nabla \cdot \vec{v}) d\tau = \int \frac{1}{r^2} \hat{r} \cdot r^2 \sin\theta d\theta d\phi \hat{r} \\ &= \int_0^\pi \sin\theta d\theta \int_0^{2\pi} d\phi = 4\pi \quad \text{origin} \end{aligned}$$



$$\delta(x) \begin{cases} 0 & \text{if } x \neq 0 \\ \infty & \text{if } x=0 \end{cases} \quad \int_{-\infty}^{\infty} \delta(x) dx = 1$$

$$\delta(x-a) \begin{cases} 0 & \text{if } x \neq a \\ \infty & \text{if } x=a \end{cases} \quad \int_{-\infty}^{\infty} \delta(x-a) dx = 1$$

If $f(x)$ is continuous, $f(x)\delta(x)$ is zero everywhere except at $x=0$

$$\text{then } f(x)\delta(x) = f(0)\delta(x), \quad \int_{-\infty}^{\infty} f(x)\delta(x) dx = f(0) \int_{-\infty}^{\infty} \delta(x) dx = f(0)$$

$$f(x)\delta(x-a) = f(a)\delta(x-a), \quad \int_{-\infty}^{\infty} f(x)\delta(x-a) dx = f(a)$$

two delta functions are considered equal $\int_{-\infty}^{\infty} f(x) D_1(x) dx = \int_{-\infty}^{\infty} f(x) D_2(x) dx$

example $\delta(kx) = \frac{1}{|k|} \delta(\frac{x}{k})$ where k is any nonzero constant Similarity Relationship

$$\begin{aligned} &\int_{-\infty}^{\infty} f(x) \delta(kx) dx \quad \text{let } y = kx, \quad x = \frac{y}{k}, \quad dx = \frac{1}{k} dy \quad \text{Scaling law} \\ &= \pm \int_{-\infty}^{\infty} f\left(\frac{y}{k}\right) \delta(y) \frac{dy}{k} \\ &= \pm \frac{1}{k} f(0) = \frac{1}{|k|} f(0) \end{aligned}$$