

# Homework #1

Student name: *Ali BaniAsad*

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Course: *Optimal Control I* – Professor: *Dr. Assadian*  
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## Problem 1

(a)  $z = f(x, y) = y \sin(x + y) - x \sin(x - y)$

Gradient of  $f(x, y)$ :

$$\vec{\nabla} f = \begin{bmatrix} \frac{\partial f}{\partial x} \\ \frac{\partial f}{\partial y} \end{bmatrix}$$

$$\vec{\nabla} f = \begin{bmatrix} y \cos(x + y) - \sin(x - y) - x \cos(x - y) \\ y \cos(x + y) + \sin(x + y) + x \cos(x - y) \end{bmatrix}$$

Two nonlinear equations with two unknowns. We use MATLAB to solve this equations. MATLAB file is attached. Answers are provided in table 8.

Table 1: Answers

x	y
-3.41877	-1.82764
-2.88904	1.84693
-2.02875	0.00000
-1.84693	-2.88904
-1.82764	3.41877
-1.75560	0.36547
-0.36547	-1.7556
0.00000	-2.02875
0.00000	0.00000
0.00000	2.02875
0.36547	1.7556
1.75560	-0.36547
1.82764	-3.41877
1.84693	2.88904
2.02875	0.00000
2.88904	-1.84693
3.41877	1.82764

Hessian matrix:

$$H = \frac{\partial^2 f}{\partial \vec{X}^2} = \begin{bmatrix} \frac{\partial^2 f}{\partial x^2} & \frac{\partial^2 f}{\partial xy} \\ \frac{\partial^2 f}{\partial yx} & \frac{\partial^2 f}{\partial y^2} \end{bmatrix}$$

$$-y \sin(x+y) - 2 \cos(x-y) + x \cos(x-y) \quad \cos(x+y) - y \sin(x+y) + \cos(x-y) - x \sin(x-y)$$

$$\cos(x+y) - y \sin(x+y) + \cos(x-y) - x \sin(x-y) \quad x \sin(x-y) + 2 \cos(x+y) - y \sin(x+y)$$

Hessian matrix and eigenvalues have calculated in MATLAB and attached.

Table 2: Answers With Conditions

x	y	Point Condition
-3.41877	-1.82764	Maximum
-2.88904	1.84693	Saddle Point
-2.02875	0.00000	Saddle Point
-1.84693	-2.88904	Saddle Point
-1.82764	3.41877	Minimum
-1.75560	0.36547	Maximum
-0.36547	-1.7556	Minimum
0.00000	-2.02875	Saddle Point
0.00000	0.00000	Saddle Point
0.00000	2.02875	Saddle Point
0.36547	1.7556	Minimum
1.75560	-0.36547	Saddle Point
1.82764	-3.41877	Minimum
1.84693	2.88904	Saddle Point
2.02875	0.00000	Saddle Point
2.88904	-1.84693	Saddle Point
3.41877	1.82764	Maximum

Answers and conditions are provided in table 2

Figure 1: 3D figure of function



Figure 2: 3D figure of function with Points



Figure 3: Contour figure of function



Figure 4: Contour figure of function with Points



(b)  $z = f(x, y) = x^3 - 3xy^2$

Gradient of  $f(x, y)$ :

$$\vec{\nabla} f = \begin{bmatrix} \frac{\partial f}{\partial x} \\ \frac{\partial f}{\partial y} \end{bmatrix}$$

$$\vec{\nabla} f = \begin{bmatrix} 3x^2 - 3y^2 \\ -6xy \end{bmatrix}$$

Two linear equations with two unknowns.

$$3x^2 - 3y^2 = 0$$

$$-6xy = 0$$

Answers is  $x = 0$  and  $y = 0$ .

Hessian matrix:

$$H = \frac{\partial^2 f}{\partial \vec{X}^2} = \begin{bmatrix} \frac{\partial^2 f}{\partial x^2} & \frac{\partial^2 f}{\partial xy} \\ \frac{\partial^2 f}{\partial yx} & \frac{\partial^2 f}{\partial y^2} \end{bmatrix}$$

$$H = \begin{bmatrix} 6x & -6y \\ -6y & -6x \end{bmatrix}$$

In  $x = 0$  and  $y = 0$  Hessian matrix in :

$$H = \begin{bmatrix} 0 & 0 \\ 0 & 0 \end{bmatrix}$$

so this point is saddle point.

Figure 5: 3D figure of function

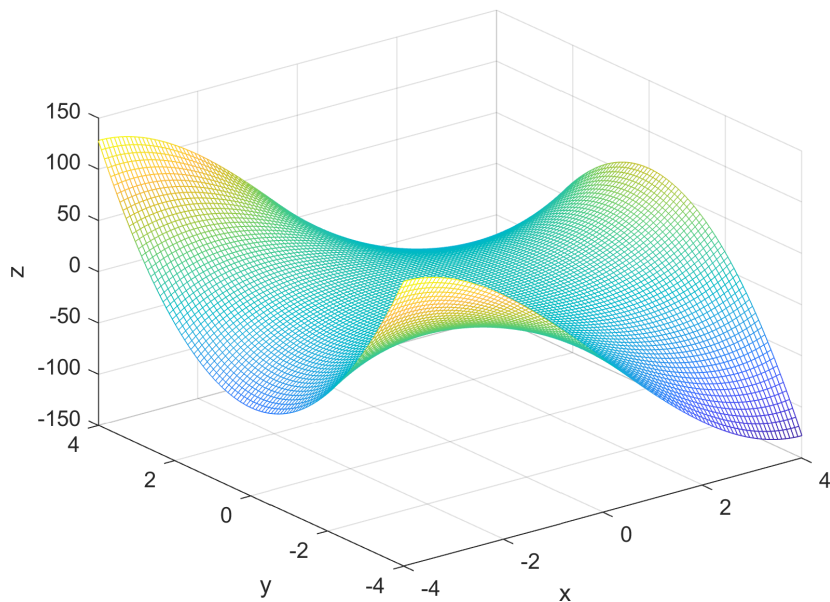


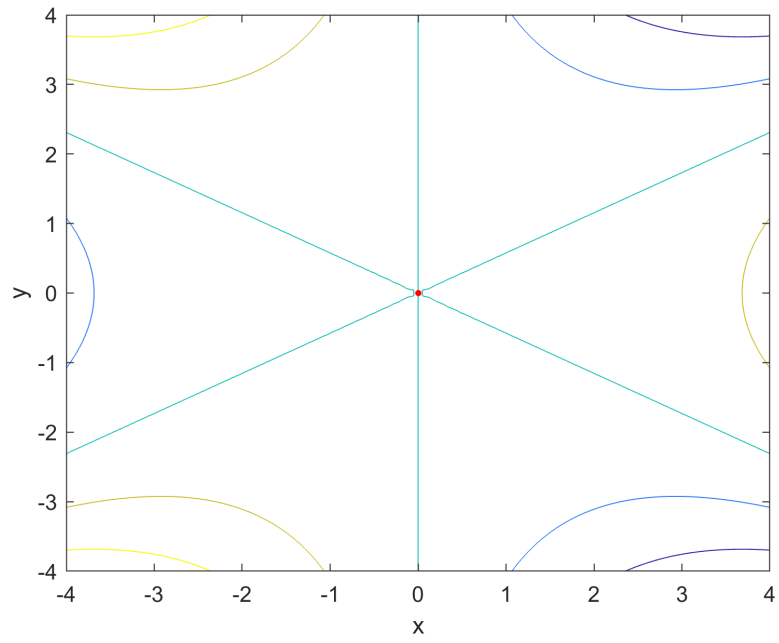
Figure 6: 3D figure of function with Points



Figure 7: Contour figure of function



Figure 8: Contour figure of function with Points



(c)  $z = f(x_1, x_2, x_3) = x_1^2 + x_1x_2 - 4x_2^2 - x_3^2 + 3x_2x_3$

Gradient of  $f(x_1, x_2, x_3)$ :

$$\vec{\nabla} f = \frac{\partial f}{\partial \vec{X}} = \begin{bmatrix} \frac{\partial f}{\partial x_1} \\ \frac{\partial f}{\partial x_2} \\ \frac{\partial f}{\partial x_3} \end{bmatrix}$$

$$\vec{\nabla} f = \begin{bmatrix} 2x_1 + x_2 \\ x_1 - 8x_2 + 3x_3 \\ 3x_2 - 2x_3 \end{bmatrix} = \vec{0}$$

Three linear equations with Three unknowns.

$$2x_1 + x_2 = 0$$

$$x_1 - 8x_2 + 3x_3 = 0$$

$$3x_2 - 2x_3 = 0$$

Answers is  $x_1 = x_2 = x_3 = 0$  Hessian matrix:

$$H = \frac{\partial^2 f}{\partial \vec{X}^2} = \begin{bmatrix} \frac{\partial^2 f}{\partial x_1^2} & \frac{\partial^2 f}{\partial x_1 x_2} & \frac{\partial^2 f}{\partial x_1 x_3} \\ \frac{\partial^2 f}{\partial x_2 x_1} & \frac{\partial^2 f}{\partial x_2^2} & \frac{\partial^2 f}{\partial x_2 x_3} \\ \frac{\partial^2 f}{\partial x_3 x_1} & \frac{\partial^2 f}{\partial x_3 x_2} & \frac{\partial^2 f}{\partial x_3^2} \end{bmatrix}$$

$$H = \begin{bmatrix} 2 & 1 & 0 \\ 1 & -8 & 3 \\ 0 & 3 & -2 \end{bmatrix}$$

All Hessian eigenvalues are:

$$eig(H) = \begin{bmatrix} -9.3182 \\ -0.8077 \\ 2.1259 \end{bmatrix}$$

So  $(0, 0, 0)$  is a saddle point.



## Problem 2

$$\min f(x, y, z) = x^2 + y^2 + z^2$$

subject to :

$$z = \sin(x) + \cos(y)$$

(a) Direct Substitution:

$$f(x, y, z) = x^2 + y^2 + z^2 \xrightarrow{z=\sin(x)+\cos(y)} f(\vec{X}) = f(x, y) = x^2 + y^2 + (\sin(x) + \cos(y))^2$$

$$f(x, y) = x^2 + y^2 + \sin(x)^2 + 2\sin(x)\cos(y) + \cos(y)^2 \text{ Gradient of } f(x, y):$$

$$\vec{\nabla} f = \begin{bmatrix} \frac{\partial f}{\partial x} \\ \frac{\partial f}{\partial y} \end{bmatrix}$$

$$\vec{\nabla} f = \begin{bmatrix} 2x + 2\cos(x)\cos(y) + 2\cos(x)\sin(x) \\ 2y - 2\cos(y)\sin(y) - 2\sin(x)\sin(y) \end{bmatrix}$$

$$2x + 2\cos(x)\cos(y) + 2\cos(x)\sin(x) = 0$$

$$2y - 2\cos(y)\sin(y) - 2\sin(x)\sin(y) = 0$$

Above equation solved in MATLAB and code (Q2\_a.m) has attached to homework.

$$x = -0.47872, \quad y = 0.0 \rightarrow z = 0.5393$$

Table 3: Answers

x	y	z
-0.47872	0.000	0.5393

(b) Lagrange multipliers:

$$\min \mathcal{L}(\vec{X}, \vec{\lambda}) = f(\vec{X}) + \vec{\lambda}^T \vec{g}$$

necessary condition:

$$\vec{\nabla} \mathcal{L} = \begin{bmatrix} \vec{\nabla}_{\vec{X}} \mathcal{L} \\ \vec{\nabla}_{\vec{\lambda}} \mathcal{L} \end{bmatrix} = \begin{bmatrix} \frac{\partial \mathcal{L}}{\partial \vec{X}} \\ \frac{\partial \mathcal{L}}{\partial \vec{\lambda}} \end{bmatrix} = \vec{0}$$

$$f(\vec{X}) = x^2 + y^2 + z^2, \quad g(\vec{X}) = \sin(x) + \cos(y) - z = 0$$

$$\min \mathcal{L}(\vec{X}, \vec{\lambda}) = x^2 + y^2 + z^2 + \lambda(\sin(x) + \cos(y) - z)$$

$$\vec{\nabla} \mathcal{L} = \begin{bmatrix} \frac{\partial \mathcal{L}}{\partial x} \\ \frac{\partial \mathcal{L}}{\partial y} \\ \frac{\partial \mathcal{L}}{\partial z} \\ \frac{\partial \mathcal{L}}{\partial \lambda} \end{bmatrix} = \begin{bmatrix} 2x + \lambda \cos(x) \\ 2y - \lambda \sin(y) \\ 2z - \lambda \\ \sin(x) + \cos(y) - z \end{bmatrix}$$

Above equation solved in MATLAB and code (Q2\_b.m) has attached to homework.

Table 4: Answers

x	y	z	$\lambda$
-0.47872	0.000	0.5393	1.078708

### Problem 3

$$\min f(x_1, x_2, y_1, y_2) = (x_1 - x_2)^2 + (y_1 - y_2)^2$$

subject to :

$$y_1 = x_1^2, \quad y_2 = x_2 - 1$$

(a) Direct Substitution:

$$f(x_1, x_2, y_1, y_2) = (x_1 - x_2)^2 + (y_1 - y_2)^2 \xrightarrow{y_1=x_1^2, y_2=x_2-1} f(x_1, x_2) = (x_1 - x_2)^2 + (x_1^2 - (x_2 - 1))^2$$

$$f(x_1, x_2) = x_1^4 - 2x_1^2x_2^2 + 4x_1^2x_2 - x_1^2 - 2x_1x_2 + x_2^4 - 4x_2^3 + 7x_2^2 - 4x_2 + 1$$

Gradient of  $f(x_1, x_2)$ :

$$\vec{\nabla} f = \begin{bmatrix} \frac{\partial f}{\partial x_1} \\ \frac{\partial f}{\partial x_2} \end{bmatrix}$$

$$\vec{\nabla} f = \begin{bmatrix} 4x_1^3 - 4x_1x_2^2 + 8x_1x_2 - 2x_1 - 2x_2 \\ -4x_1^2x_2 + 4x_1^2 - 2x_1 + 4x_2^3 - 12x_2^2 + 14x_2 - 4 \end{bmatrix}$$

Two nonlinear equations with two unknowns. We use MATLAB to solve this equations. MATLAB file (Q3\_a.m) is attached.

$$4x_1^3 - 4x_1x_2^2 + 8x_1x_2 - 2x_1 - 2x_2 = 0$$

$$-4x_1^2x_2 + 4x_1^2 - 2x_1 + 4x_2^3 - 12x_2^2 + 14x_2 - 4 = 0$$

$$x_1 = \frac{1}{2} \rightarrow y_1 = \frac{1}{4}, \quad x_2 = \frac{7}{8} \rightarrow y_2 = -\frac{1}{8}$$

Table 5: Answers

$x_1$	$y_1$	$x_2$	$y_2$
0.5	0.25	0.875	-0.125

(b) Lagrange multipliers:

$\min \mathcal{L}(\vec{X}, \vec{\lambda}) = f(\vec{X}) + \vec{\lambda}^T \vec{g}$  necessary condition:

$$\vec{\nabla} \mathcal{L} = \begin{bmatrix} \vec{\nabla}_{\vec{X}} \mathcal{L} \\ \vec{\nabla}_{\vec{\lambda}} \mathcal{L} \end{bmatrix} = \begin{bmatrix} \frac{\partial \mathcal{L}}{\partial \vec{X}} \\ \frac{\partial \mathcal{L}}{\partial \vec{\lambda}} \end{bmatrix} = \vec{0}$$

$$f(\vec{X}) = (x_1 - x_2)^2 + (y_1 - y_2)^2, \quad g(\vec{X}) = [y_1 - x_1^2 \quad y_2 - x_2 + 1] = \vec{0}$$

$$\min \mathcal{L}(\vec{X}, \vec{\lambda}) = (x_1 - x_2)^2 + (y_1 - y_2)^2 + \lambda_1(y_1 - x_1^2) + \lambda_2(y_2 - x_2 + 1)$$

$$\vec{\nabla} \mathcal{L} = \begin{bmatrix} \frac{\partial \mathcal{L}}{\partial x_1} \\ \frac{\partial \mathcal{L}}{\partial y_1} \\ \frac{\partial \mathcal{L}}{\partial x_2} \\ \frac{\partial \mathcal{L}}{\partial y_2} \\ \frac{\partial \mathcal{L}}{\partial \lambda_1} \\ \frac{\partial \mathcal{L}}{\partial \lambda_2} \end{bmatrix} = \begin{bmatrix} 2x_1 - 2x_2 - 2\lambda_1x_1 \\ 2y_1 - 2y_2 + \lambda_1 \\ 2x_2 - 2x_1 - \lambda_2 \\ 2y_2 - y_1 + \lambda_2 \\ y_1 - x_1^2 \\ y_2 - x_2 + 1 \end{bmatrix}$$

Six nonlinear equations with six unknowns. We use MATLAB to solve this equations. MATLAB file (Q3.b.m) is attached.

Table 6: Answers

$x_1$	$y_1$	$x_2$	$y_2$	$\lambda_1$	$\lambda_2$
0.5	0.25	0.875	-0.125	-0.75	0.75

(c) Calculus of Variation:

Euler–Lagrange equation:

$$g_x - \frac{d}{dt}g_{\dot{x}} = 0$$

In problem g function is that we must minimize is:

$$g(\dot{x}, x, t) = g(\dot{x}) = \sqrt{1 + \dot{x}^2} =$$

$$\rightarrow \frac{\partial g_{\dot{x}}}{\partial \dot{x}} \frac{\dot{x}}{dt} = 0 \rightarrow g_{\dot{x}\dot{x}}\ddot{x} = 0$$

The solution is line:

$$\rightarrow x(t) = c_1 t + c_2$$

Boundary condition:

Initial time:  $\theta(t) = t^2$

$$(g + (\dot{\theta} - \dot{x})g_{\dot{x}})|_{t=t_0} = 0 \rightarrow \sqrt{1 + \dot{x}^2} + (2t - \dot{x})\frac{\dot{x}}{\sqrt{1 + \dot{x}^2}}|_{t=t_0} = 0 \rightarrow t_0 = -\frac{1}{2\dot{x}}|_{t=t_0}$$

Final time:  $\theta(t) = t - 1$

$$(g + (\dot{\theta} - \dot{x})g_{\dot{x}})|_{t=t_f} = 0 \rightarrow \sqrt{1 + \dot{x}^2} + (1 - \dot{x})\frac{\dot{x}}{\sqrt{1 + \dot{x}^2}}|_{t=t_f} = 0 \rightarrow \dot{x}_f = -1$$

Because of x function  $\dot{x}$  is constant in  $t_0 \rightarrow t_f$ ,

$$\rightarrow c_1 = -1 \rightarrow t_0 = \frac{1}{2\dot{x}}|_{t=t_0} = -\frac{1}{2c_1} = \frac{1}{2} \rightarrow x_0 = \frac{1}{4}$$

$$x(t) = c_1 t + c_2 \rightarrow x(t_0) = c_1 t_0 + c_2 \rightarrow c_2 = 0.75$$

Final time:

$$x(t_f) = \theta(t_f) \rightarrow -t_f + 0.75 = t_f - 1 \rightarrow t_f = 0.875 \xrightarrow{x(t)=-t+0.75} x_f = -0.125$$

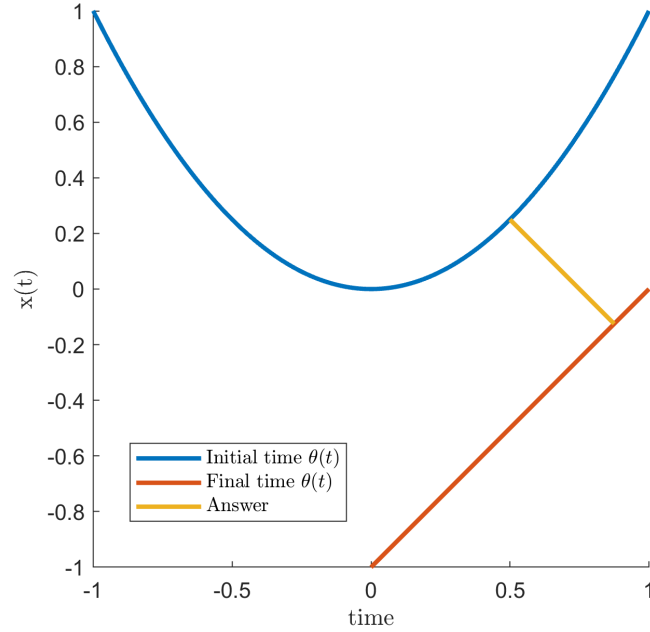
Answer:

$$x(t) = -t + 0.75t_0 \rightarrow t_f$$

Table 7: Answers

$t_0$	$x_0$	$t_f$	$x_f$
0.5	0.25	0.875	-0.125

Figure 9: Answer function



- (d) From last part we know that answer is a line but in this question we must minimize two cost function so there is two line and seven unknowns.

Equations:

$$x_1(t) = c_1 t + c_2 \quad 0 \leq t \leq t_1$$

$$x_2(t) = c_3 t + c_4 \quad t_1 \leq t \leq t_f$$

Boundary condition:

Initial time:  $\theta_0(t) = t^2$

$$(g + (\dot{\theta} - \dot{x})g_{\dot{x}})|_{t=t_0} = 0 \rightarrow \sqrt{1 + \dot{x}^2} + (2t - \dot{x}) \frac{\dot{x}}{\sqrt{1 + \dot{x}^2}}|_{t=t_0} = 0 \rightarrow t_0 = -\frac{1}{2\dot{x}}|_{t=t_0}$$

$$\rightarrow t_0 = -\frac{1}{2c_1} \rightarrow t_0 + \frac{1}{2c_1} = 0$$

$$\theta_0(t_0) = x_1(t_0) = t_0^2 = c_1 t_0 + c_2 \rightarrow t_0^2 - c_1 t_0 - c_2 = 0$$

Final time:  $\theta_f(t) = t - 1$

$$(g + (\dot{\theta} - \dot{x})g_{\dot{x}})|_{t=t_f} = 0 \rightarrow \sqrt{1 + \dot{x}^2} + (1 - \dot{x}) \frac{\dot{x}}{\sqrt{1 + \dot{x}^2}}|_{t=t_f} = 0 \rightarrow \dot{x}_f = -1$$

$$\rightarrow c_3 = -1$$

$$\theta_f(t_f) = x_2(t_f) = t_f - 1 = -t_f + c_4 \rightarrow 2t_f - c_4 - 1 = 0$$

Corner conditions:  $\theta_c(t) = 4 + 2(t - 4)^2$

$$(g + (\dot{\theta} - \dot{x})g_{\dot{x}})|_{t=t_1^-} = (g + (\dot{\theta} - \dot{x})g_{\dot{x}})|_{t=t_1^+}$$

$$\rightarrow -4t_1 + 16 = 4t_1 c_1 - 16c_1 \rightarrow 4t_1(c_1 + 1) - 16c_1 - 16 = 0$$

In  $t = t_1$ :

$$\theta_0(t_1) = \theta_f(t_1) \rightarrow c_1 t_1 + c_2 = -t_1 + c_4$$

$$\begin{aligned}
c_1 t_1 + c_2 + t_1 - c_4 &= 0 \\
\theta_0(t_1) &= \theta_c(t_1) = \theta_f(t_1) \\
\rightarrow c_1 t_1 + c_2 &= 4 + 2(t_1 - 4)^2 \rightarrow 2(t_1 - 4)^2 + 4 - c_1 t_1 - c_2 = 0
\end{aligned}$$

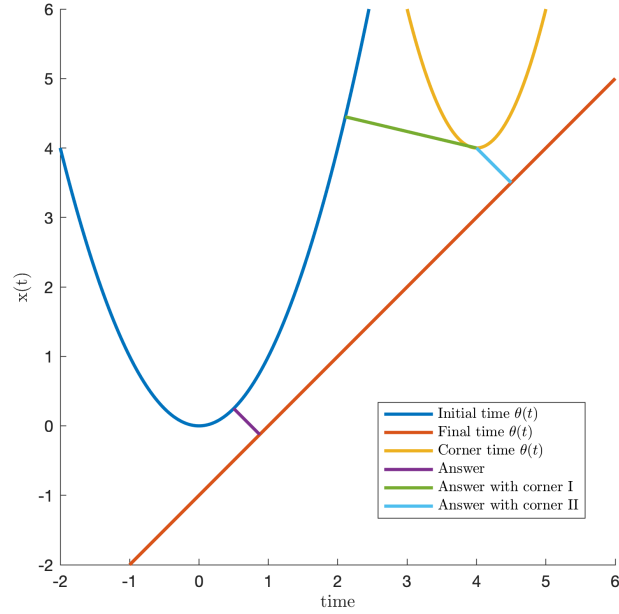
The above equations solved if MATLAB (Q3\_d.m).

Table 8: Answers

$t_0$	$x_0$	$t_1$	$x_1$	$t_f$	$x_f$
2.11	4.448	4	4	4.5	3.5

$$x_1(t) = -0.237t + 4.9483, \quad x_2(t) = -t + 8$$

Figure 10: Answer function with corner



#### Problem 4

Potential function:

$$dP = x g_0 dm = x g_0 \rho_s ds = x g_0 \rho_s \sqrt{1 + \dot{x}^2} dt \rightarrow dP = g_0 \rho_s x \sqrt{1 + \dot{x}^2} dt \rightarrow P = \int_{t_0}^{t_f} g_0 \rho_s x \sqrt{1 + \dot{x}^2} dt$$

$$P = g_0 \rho_s \int_{t_0}^{t_f} x \sqrt{1 + \dot{x}^2} dt$$

$$\min J(\dot{x}, x) = \int_{t_0}^{t_f} x \sqrt{1 + \dot{x}^2} dt$$

length of rope is L so problem subject to:

$$z(t) = \int_{t_0}^t \sqrt{1 + \dot{x}^2} dt = L$$

$z(t)$  is new state:

$$z(t) = \int_{t_0}^{t_f} \sqrt{1 + \dot{x}^2} dt \rightarrow \frac{dz}{dt} = \sqrt{1 + \dot{x}^2}$$

New differential constraints:

$$\begin{aligned} \frac{dz}{dt} - \sqrt{1 + \dot{x}^2} &= 0 \\ g_a(x, \dot{x}, \dot{z}, t, \lambda) &= g_a(x, \dot{x}, t) + \lambda(t)f(x, \dot{x}, \dot{z}, t) \\ g_a &= x\sqrt{1 + \dot{x}^2} + \lambda(\dot{z} - \sqrt{1 + \dot{x}^2}) \end{aligned}$$

Euler–Lagrange equation:

$$\begin{aligned} \frac{\partial g_a}{\partial x} - \frac{d}{dt} \frac{\partial g_a}{\partial \dot{x}} &= 0 \\ \frac{\partial g_a}{\partial \lambda} - \frac{d}{dt} \frac{\partial g_a}{\partial \dot{\lambda}} &= 0 \rightarrow \dot{z} - \sqrt{1 + \dot{x}^2} = 0 \\ \frac{\partial g_a}{\partial \dot{z}} - \frac{d}{dt} \frac{\partial g_a}{\partial \dot{\dot{z}}} &= 0 \rightarrow \lambda = C \end{aligned}$$

$\lambda$  is constant.

$$\begin{aligned} \frac{\partial g_a}{\partial x} &= \sqrt{1 + \dot{x}^2} \\ g_{a_{\dot{x}}} &= \frac{\partial g_a}{\partial \dot{x}} = \frac{x\dot{x}}{\sqrt{1 + \dot{x}^2}} - \frac{\lambda\dot{x}}{\sqrt{1 + \dot{x}^2}} \\ \frac{d}{dt} \frac{\partial g_a}{\partial \dot{x}} &= \frac{\partial g_{a_{\dot{x}}}}{\partial t} + \frac{\partial g_{a_{\dot{x}}}}{\partial x} \dot{x} + \frac{\partial g_{a_{\dot{x}}}}{\partial \dot{x}} \ddot{x} + \frac{\partial g_{a_{\dot{x}}}}{\partial \ddot{x}} \ddot{\dot{x}} \end{aligned}$$

$g$  is a function of  $x$  and  $\dot{x}$  so:

$$g - \dot{x}g_{\dot{x}} = a$$

$a$  is constant.

$$\begin{aligned} \frac{x - \lambda}{\sqrt{1 + \dot{x}^2}} &= a \rightarrow dt = \frac{a dx}{\sqrt{(x - \lambda)^2 - a^2}} \\ x(t) &= \lambda + a \cosh\left(\frac{t - b}{a}\right) \end{aligned}$$

Boundary conditions:

$$t_0 = 0, \quad t_f = t_f, \quad x(t_0) = 0, \quad x(t_f) = 0, \quad z(t_0) = 0, \quad z(t_f) = L$$

$$\int_{t_0}^{t_f} \sqrt{1 + \dot{x}^2} = \int_0^{t_f} \cosh\left(\frac{t - b}{a}\right) = L$$

$$a \sinh\left(\frac{t_f - b}{a}\right) = L \tag{1}$$

$$\lambda + a \cosh\left(\frac{-b}{a}\right) = 0 \tag{2}$$

$$\lambda + a \cosh\left(\frac{t_f - b}{a}\right) = 0 \tag{3}$$

Three nonlinear equations with Three unknowns.

### Problem 5

(a)  $g = \sin(\dot{x}^2)$

$g$  is only a function of  $\dot{x}$  so the answer is a line.

Answer:  $c_1 t + c_2$

Final time is fix and final location is free so the boundary condition is:

$$g_{\dot{x}}|_{t_f} = 0 \rightarrow 2\dot{x}_{t_f} \cos(\dot{x}_{t_f}^2) = 0 \xrightarrow{x(t)=c_1 t + c_2} 2c_1 \cos(c_1^2) = 0$$

$$\rightarrow c_1 = \pm\sqrt{\frac{\pi}{2}}, \quad c_1 = 0, \quad c_1 = \pm\sqrt{\frac{3\pi}{2}}$$

$$J(x) = \int_0^2 \sin(\dot{x}^2) \xrightarrow{c_1 = \pm\sqrt{\frac{\pi}{2}}} J(x) = 2 \quad (4)$$

$$J(x) = \int_0^2 \sin(\dot{x}^2) \xrightarrow{c_1 = 0} J(x) = 0 \quad (5)$$

$$J(x) = \int_0^2 \sin(\dot{x}^2) \xrightarrow{c_1 = \pm\sqrt{\frac{3\pi}{2}}} J(x) = -2 \quad (6)$$

The point  $c_1 = \pm\sqrt{\frac{\pi}{2}}$  is maximum,  $c_1 = 0$  is saddle and  $c_1 = \pm\sqrt{\frac{3\pi}{2}}$  is minimum.

In  $t_f$   $x(t_0) = 1$  so  $c_2$  is one.

Maximum  $J(x)$

$$x(t) = \pm\sqrt{\frac{\pi}{2}}t + 1$$

Saddle  $J(x)$

$$x(t) = 1$$

Maximum  $J(x)$

$$x(t) = \pm\sqrt{\frac{3\pi}{2}}t + 1$$

(b)  $g = t\dot{x}^2(t) + \ln(\dot{x}^2(t))$

$g$  is a function of  $\dot{x}$  and  $t$  so:

$$\frac{dg_{\dot{x}}}{dt} = 0 \rightarrow g_{\dot{x}} = C$$

$C$  is constant.

$$g_{\dot{x}} = 2t\dot{x} + \frac{2}{\dot{x}} \rightarrow \dot{x}^2 + \dot{x}\left(\frac{2-C}{2t}\right) = 0$$

Above equation solved with MATLAB(Q5\_d.m).

Answer:

There is two answer for above differential equation:

- first

$$x(t) = C_1$$

- second

$$C_2 + \ln(t)(C/2 - 1)$$

Boundary conditions:

$$x(0) = 1, \quad x(2) = 2$$

With those boundary conditions there is no acceptable answer.



(c)  $g = \dot{x}_1^2 + \dot{x}_2^2 - 2x_1x_2$  Euler-Lagrange equation:

$$\frac{\partial g_{\vec{x}}}{\partial \vec{x}} - \frac{d}{dt} \frac{\partial g_{\vec{x}}}{\partial \dot{\vec{x}}} = 0$$

$$\begin{bmatrix} \frac{\partial g}{\partial x_1} \\ \frac{\partial g}{\partial x_2} \end{bmatrix} - \frac{d}{dt} \begin{bmatrix} \frac{\partial g}{\partial \dot{x}_1} \\ \frac{\partial g}{\partial \dot{x}_2} \end{bmatrix} = \begin{bmatrix} -2x_2 + 2\ddot{x}_1 \\ -2x_1 + 2\ddot{x}_2 \end{bmatrix} = 0$$

We can find out from above equation that  $x_2 = \ddot{x}_2$  and this equation solve in MATLAB(Q5.c.m).

$$x_1(t) = C_3 \cos(t) - C_2 \exp(t) - C_4 \sin(t) - C_1 \exp(-t)$$

$$x_2(t) = C_3 \cos(t) + C_2 \exp(t) - C_4 \sin(t) + C_1 \exp(-t)$$

On of the boundry conditions are free so we must make another equation.

$$g_{\dot{x}_2}|_{t_f} = 0 \rightarrow \dot{x}_2(t_f) = 0$$

Boundary conditions:

$$x_1(0) = x_2(0) = 1, \quad x_1(\pi) = 4, \quad \dot{x}_2(\pi) = 0$$

$$C_3 - C_2 - C_1 = 1, \quad C_3 + C_2 + C_1 = 1, \quad -C_3 - C_2 \exp(\pi) - C_1 \exp(-\pi) = 4$$

$$C_3 = 1, \quad C_1 = -C_2 = \frac{5}{\exp(\pi) - \exp(-\pi)}$$

$$-C_1 \exp(-\pi) + C_2 \exp(\pi) + C_4 = 0 \rightarrow C_4 = \frac{10(\exp(\pi) + \exp(-\pi))}{\exp(\pi) - \exp(-\pi)}$$

$$x_1(t) = \cos(t) - \frac{5}{\exp(-\pi) - \exp(\pi)} \exp(t) - \frac{10(\exp(\pi) + \exp(-\pi))}{\exp(\pi) - \exp(-\pi)} \sin(t) - \frac{5}{\exp(\pi) - \exp(-\pi)} \exp(-t)$$

$$x_2(t) = \cos(t) + \frac{5}{\exp(-\pi) - \exp(\pi)} \exp(t) - \frac{10(\exp(\pi) + \exp(-\pi))}{\exp(\pi) - \exp(-\pi)} \sin(t) + \frac{5}{\exp(\pi) - \exp(-\pi)} \exp(-t)$$

(d)  $g(x, \dot{x}, \ddot{x}) = x^2 + 2\dot{x}^2 + \ddot{x}$

Euler-Lagrange equation:

$$\frac{\partial g}{\partial x} - \frac{d}{dt} \frac{\partial g}{\partial \dot{x}} + \frac{d^2}{dt^2} \frac{\partial g}{\partial \ddot{x}} = 0$$

$$\frac{\partial g}{\partial x} = 2x, \quad \frac{\partial g}{\partial \dot{x}} = 4\dot{x}, \quad \frac{\partial g}{\partial \ddot{x}} = 2\ddot{x}$$

In below equation we use this syntax:

$$\frac{\partial g}{\partial \ddot{x}} = g_{\dot{x}}, \quad \frac{\partial g}{\partial \ddot{x}} = g_{\ddot{x}}$$

$$\frac{dg_{\dot{x}}}{dt} = \frac{\partial g_{\dot{x}}}{\partial t} + \frac{\partial g_{\dot{x}}}{\partial x} \dot{x} + \frac{\partial g_{\dot{x}}}{\partial \dot{x}} \ddot{x} + \frac{\partial g_{\dot{x}}}{\partial \ddot{x}} \ddot{\ddot{x}} = 4\ddot{x}$$

$$\frac{dg_{\ddot{x}}}{dt} = \frac{\partial g_{\ddot{x}}}{\partial t} + \frac{\partial g_{\ddot{x}}}{\partial x} \dot{x} + \frac{\partial g_{\ddot{x}}}{\partial \dot{x}} \ddot{x} + \frac{\partial g_{\ddot{x}}}{\partial \ddot{x}} \ddot{\ddot{x}} = 2\ddot{\ddot{x}}$$

$$\frac{d^2}{dt^2} \frac{\partial g}{\partial \ddot{x}} = \frac{\partial(\frac{dg_{\ddot{x}}}{dt})}{\partial t} + \frac{\partial(\frac{dg_{\ddot{x}}}{dt})}{\partial x} \dot{x} + \frac{\partial(\frac{dg_{\ddot{x}}}{dt})}{\partial \dot{x}} \ddot{x} + \frac{\partial(\frac{dg_{\ddot{x}}}{dt})}{\partial \ddot{x}} \ddot{\ddot{x}} + \frac{\partial(\frac{dg_{\ddot{x}}}{dt})}{\partial \ddot{\ddot{x}}} \ddot{\ddot{\ddot{x}}} = 2\ddot{\ddot{\ddot{x}}}$$

Euler-Lagrange equation:

$$2\ddot{\ddot{x}} - 4\ddot{x} + 2x = 0 \rightarrow \ddot{\ddot{x}} - 2\ddot{x} + x = 0$$

Above differential equation solve with MATLAB(Q5.5d.m). Answer:

$$x(t) = C_3 \exp(t) + C_1 \exp(-t) + C_2 t \exp(-t) + C_4 t \exp(t)$$

$$\dot{x}(t) = (C_3 + C_4 + C_4 t) \exp(t) + (C_2 - C_2 - C_2 t) \exp(-t)$$

Boundary conditions:

$$x(0) = 1, \quad \dot{x}(0) = 2, \quad x(\infty) = \dot{x}(\infty) = 0$$

$$C_1 + C_3 = 1, \quad C_4 = C_3 = 0, \quad C_2 - C_1 = 2$$

$$x(t) = \exp(-t) + 3t \exp(-t)$$

(e) minimize:

$$\int_0^1 (x^2(t) + \dot{x}^2(t)) dt$$

Subjected to:

$$\int_0^1 x(t) dt = 1$$

$z(t)$  is new state:

$$z(t) = \int_0^t x(t) dt \rightarrow \frac{dz}{dt} = x(t)$$

New  $g$  function:

$$g_a(x, \dot{x}, \dot{z}, \lambda, t) = g_a(x, \dot{x}, t) + \lambda(t) f(x, \dot{z}, t)$$

Euler-Lagrange equation:

$$\frac{\partial g_a}{\partial x} - \frac{d}{dt} \frac{\partial g_a}{\partial \dot{x}} = 0$$

$$\frac{\partial g_a}{\partial \lambda} - \frac{d}{dt} \frac{\partial g_a}{\partial \dot{\lambda}} = 0 \rightarrow \dot{z} - x(t) = 0$$

$$\frac{\partial g_a}{\partial z} - \frac{d}{dt} \frac{\partial g_a}{\partial \dot{z}} = 0 \rightarrow \lambda = C$$

$\lambda$  is constant.

$$\frac{\partial g_a}{\partial x} = 2x - \lambda$$

$$g_{a_{\dot{x}}} = 2\dot{x}$$

$$\frac{d}{dt} \frac{\partial g_a}{\partial \dot{x}} = \frac{\partial g_{a_{\dot{x}}}}{\partial t} + \frac{\partial g_{a_{\dot{x}}}}{\partial x} \dot{x} + \frac{\partial g_{a_{\dot{x}}}}{\partial \dot{x}} \ddot{x} + \frac{\partial g_{a_{\dot{x}}}}{\partial \ddot{x}} \ddot{\ddot{x}} = 2\ddot{x}$$

Euler-Lagrange equation:

$$\ddot{x} - 2x + \lambda = 0$$

Above differential equation solve with MATLAB(Q5.5e.m). Answer:

$$x(t) = C_1 \exp(\sqrt{2}t) + C_2 \exp(-\sqrt{2}t) + \lambda/2$$

Boundary conditions:

$$\int_0^1 x(t) dt = 1 \rightarrow \frac{\sqrt{2}}{2} C_1 \exp(\sqrt{2}t) - \frac{\sqrt{2}}{2} C_2 \exp(-\sqrt{2}t) + \lambda t/2 \Big|_0^1$$

$$x(0) = C_1 + C_2 + \lambda/2 = 0$$

$$x(1) = C_1 \exp(\sqrt{2}) + C_2 \exp(-\sqrt{2}) + \lambda/2 = 1$$

There is There nonlinear equation and there Unknowns. Above differential equation solve with MATLAB(Q5.5e.m).

Answers:

$$C_1 = \frac{1}{\exp(\sqrt{2}) - \exp(-\sqrt{2})}, \quad C_2 = \frac{-1}{\exp(\sqrt{2}) - \exp(-\sqrt{2})}, \quad \lambda = 0$$

$$x(t) = \frac{\exp(\sqrt{2}t)}{\exp(\sqrt{2}) - \exp(-\sqrt{2})} + \frac{-\exp(-\sqrt{2}t)}{\exp(\sqrt{2}) - \exp(-\sqrt{2})}$$

(f)  $g = \frac{\sqrt{1 + \dot{x}^2}}{x}$

Euler–Lagrange equation:

$$\frac{\partial g}{\partial x} - \frac{d}{dt} \frac{\partial g}{\partial \dot{x}} = 0$$

$g$  is a function of  $x$  and  $\dot{x}$  so:

$$g - \dot{x} g_{\dot{x}} = C$$

$C$  is constant.

$$g_{\dot{x}} = \frac{\dot{x}}{x\sqrt{1 + \dot{x}^2}}$$

$$\frac{1}{x\sqrt{1 + \dot{x}^2}} = C$$

Above equation solved in MATLAB(Q5.f.m) with boundary condition  $x(0) = 0$ .

$$x(t) = \pm \frac{\sqrt{-ct(ct+2)}}{c}$$

Final time:  $(t_f - 9)^2 + x^2(t_f) = 9$

We can change  $\theta_t$  to:

$$\theta(t) = \pm \sqrt{9 - (t_f - 9)^2}$$

$$(g + (\dot{\theta} - \dot{x})g_{\dot{x}})\Big|_{t=t_f} = 0 \rightarrow (9 - t_f)^2(\dot{x}_{t_f}^2 - 1) = 9$$

$$\dot{x} = \pm \frac{ct - 1}{\sqrt{-ct(ct - 2)}}$$

$$(t_f - 9)^2 + \frac{-t_f(ct_f + 2)}{c} = 9$$

$$(9 - t_f)^2 \left( \frac{(ct_f - 1)^2}{-ct_f(ct_f - 2)} \right) = 9$$

There is two equation and two unknowns.