Math, Science, and Engineering Handbook

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1 Math

1.1 Integrals

1 $\int x^n \, dx = \frac{x^{n+1}}{n+1}$
2 $\int \frac{dx}{x} = lnx$
3 $\int e^x \, dx = e^x$
4 $\int cos(x) \, dx = sin(x)$
5 $\int sin(x) \, dx = -cos(x)$
6 $\int sec^2(x) \, dx = tan(x)$
7 $\int csc^2(x) \, dx = -cot(x)$
8 $\int sec(x) \cdot tan(x) \, dx = sec(x)$
9 $\int csc(x) \cdot cot(x) \, dx = -csc(x)$
10 $\int \frac{dx}{\sqrt{a^2-x^2}} = sin^{-1}(\frac{x}{a})$
11 $\int \frac{dx}{a^2+x^2} = \frac{1}{a}tan^{-1}(\frac{x}{a})$
12 $\int tan(x) \, dx = -ln(cos(x))$
13 $\int cot(x) \, dx = ln(sin(x))$
14 $\int sec(x) \, dx = ln(sec(x) + tan(x))$
15 $\int csc(x) \, dx = -ln(csc(x) + cot(x))$

1.2 Formulas

Quadratic Approximation	$f(u + x) \ = f(u) + f'(u) \cdot x + f''(u) \cdot x^2/2$
$FTC2$	$d/dx \int_0^x f(t)dt = f(x)$
$FTC2$ Chain Rule	$d/dx \int_0^{g(x)} f(t)dt = g'(x) \cdot f(g(x))$
Weighted Average	$\int_a^b f(x)w(x)dx / \int_a^b w(x)dx$

1.3 L'Hôpital's Rule

$$\lim_{x \to a} f(x)/g(x) = \lim_{x \to a} f'(x)/g'(x)$$

0/0	Straight up
∞/∞	Straight up
$0 \cdot \infty$	Rewrite as quotient
0^0	Rewrite as $e^{ln(f)}$
∞^0	Rewrite as $e^{ln(f)}$
1^∞	Rewrite as $e^{ln(f)}$
$\infty - \infty$	Good luck
Otherwise	Forget it.

1.4 Vector Products

Dot Product

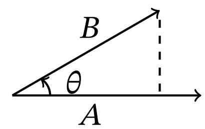

Figure 1: Dot Product

$\vec{A} \cdot \vec{B} = \left|\vec{A}\right| \left|\vec{B}\right| cos(\theta)$

The scalar value of the dot product is the sum of the product of the vector components $\Sigma\, a_i \cdot b_i$

Geometrically, the scalar value is the length of the projection of $\vec{B}$ onto $\vec{A}$.

Cross Product

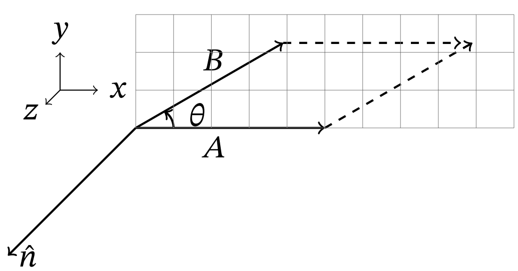

Figure 2: Cross Product

$\vec{A} \times \vec{B} = \left|\vec{A}\right| \left|\vec{B}\right| sin(\theta)\hat{n}$

Geometrically, the vector value of the cross product is the area of the parallelogram formed by $\vec{B}$ and $\vec{A}$ times the unit vector $\hat{n}$ normal to the plane of the parallelogram following the right hand rule.

Special Values

$\vec{A} \cdot \vec{B} > 0$	θ is acute.
$\vec{A} \cdot \vec{B} < 0$	θ is obtuse.
$\vec{A} \cdot \vec{B} = 0$	Vectors are orthogonal.
$\vec{A} \times \vec{B} = 0$	Vectors are parallel.

1.5 Parametric Vector Calculus

Position			$\vec{r}(t) = x(t)\hat{\imath} + y(t)\hat{\jmath}$	$\int \vec{v}(t)dt$	
Velocity	$d\vec{r}(t)/dt$		$\vec{v}(t) = x'(t)\hat{\imath} + y'(t)\hat{\jmath}$	$\int \vec{a}(t)dt$	$\frac{ds}{dt}\vec{T}$
Acceleration	$d\vec{v}(t)/dt$	$d^2\vec{r}(t)/dt^2$	$\vec{v}(t) = x''(t)\hat{\imath} + y''(t)\hat{\jmath}$		
Arc Length	$\frac{ds}{dt} = \sqrt{x'(t)\hat{\imath} + y'(t)\hat{\jmath}}$				
Unit Tangent	$\vec{T} = \vec{v}/\left\|\vec{v}\right\|$				

1.6 Partial Differentiation

Tangent Plane to $f(x_0, y_0)$	$z - z_0 = (\frac{\partial f}{\partial x})_{x_0}(x - x_0) + (\frac{\partial f}{\partial y})_{y_0}(y - y_0)$
Approximation	$f(x, y) = z_0 + \frac{\partial f}{\partial x}(x - x_0) + \frac{\partial f}{\partial y}(y - y_0)$

1.7 Least Square Line

$\begin{pmatrix} \sum x_i^2 & \sum x_i \\ \sum x_i & n \end{pmatrix}^{-1} \begin{pmatrix} \sum x_i y_i \\ \sum y_i \end{pmatrix} = \begin{pmatrix} a \\ b \end{pmatrix}$ for $y = ax + b$ given n points (x_i, y_i)

1.8 Second Derivative Test

Given $f(x, y)$ critical points (x_c, y_c) where $\frac{\partial f}{\partial x} = 0$ and $\frac{\partial f}{\partial y} = 0$

$A = \frac{\partial^2 f}{\partial x^2} @ (x_c, y_c)$

$B = \frac{\partial^2 f}{\partial x \partial y} @ (x_c, y_c)$

$C = \frac{\partial^2 f}{\partial y^2} @ (x_c, y_c)$

$AC - B^2 > 0$, $A > 0$ or $C > 0$	Minimum point
$AC - B^2 > 0$, $A < 0$ or $C < 0$	Maximum point
$AC - B^2 < 0$	Saddle point
$AC - B^2 = 0$	Need higher order terms to conclude

1.9 Differential Chain Rule

$f(x(t), y(t), z(t))$; $\frac{df}{dt} = f_x \frac{dx}{dt} + f_y \frac{dy}{dt} + f_z \frac{dz}{dt}$

1.10 Level Curves and Surfaces

The *level curve* for a function $f(x, y)$ is the set of points (x, y) where $f(x, y) = C$ for constant C.

1.11 Gradient

The *gradient* ∇f of (*potential*) function f is a vector of the partial derivatives of f for each independant variable; e.g. $\nabla f(x, y) = \langle f_x, f_y \rangle$. $\nabla f \perp f(x, y)$, i.e. *gradient* $\perp$ *level curve*.

The *directional derivitive* of f at the point P in the direction of $\vec{u}$ is $\left.\frac{df}{ds}\right|_{P,\vec{u}} = \nabla f(P) \cdot \vec{u}$.

Given an *objective* function f and a *constraint* function $g = C$ for constant C, the *extrema* of f are found when $\nabla f \parallel \nabla g$. The *Lagrange multiplier* λ is $\frac{\nabla f}{\nabla g}$.

1.12 Center of Mass

M	Mass
δ	Density Function
$\bar{x}$	x center
$\bar{y}$	y center

$$M = \int \int_R \delta \, dA$$
$$\bar{x} = \frac{1}{M} \int \int_R x\delta \, dA$$
$$\bar{y} = \frac{1}{M} \int \int_R y\delta \, dA$$

1.13 Moment of Inertia

I_x	Moment about x axis
I_y	Moment about y axis

$$I_x = \int \int_R \delta y^2 \, dy$$
$$I_y = \int \int_R \delta x^2 \, dx$$

1.14 Change of Variables

$$\int\int_R f(x,y)\,dx\,dy = \int\int_R g(u,v)\,|J|\,du\,dv$$
$$g(u,v) = f(x(u,v),y(u,v))$$
$$|J| = \left|\frac{\partial(x,y)}{\partial(u,v)}\right| = \begin{vmatrix} \frac{\partial x}{\partial u} & \frac{\partial x}{\partial v} \\ \frac{\partial y}{\partial u} & \frac{\partial y}{\partial v} \end{vmatrix}$$
$$\left|\frac{\partial(x,y)}{\partial(u,v)}\right| \cdot \left|\frac{\partial(u,v)}{\partial(x,y)}\right| = 1$$

1.15 Vector Field

$\vec{F}$	Field	
M	Field component in x direction ($\hat{\imath}$)	F_x
N	Field component in y direction ($\hat{\jmath}$)	F_y
C	Curve $\vec{r}(t) = \langle x(t), y(t)\rangle$	

$$\vec{F}(x,y) = \langle M, N\rangle$$
$$\vec{F}(x,y) = M(x,y)\hat{\imath} + N(x,y)\hat{\jmath}$$
$$\operatorname{curl}\vec{F} = N_x - M_y$$
$$\operatorname{div}\vec{F} = M_x + N_y$$

1.16 Rectangular/Polar Conversion

$$x = r\,cos(\theta)$$
$$y = r\,sin(\theta)$$
$$\theta = tan^{-1}(y/x)$$
$$r = \sqrt{x^2+y^2}$$
$$dx\,dy = r\,dr\,d\theta$$

1.17 Complex Arithmetic

$i = \sqrt{-1}$	Imaginary unit
$z = a + bi$	Complex number z
$\bar{z} = a - bi$	Complex congugate
$a = Re(a + bi)$	Real part
$b = Im(a + bi)$	Imaginary part
$(a + bi) + (c + di) = (a + c) + (b + d)i$	Addition
$(a + bi) \cdot (c + di) = (ac - bd) + (ad + bc)i$	Multiplication
$\frac{a + bi}{c + di} = \frac{(ac + bd) + (bc - ad)i}{c^2 + d^2}$	Division
$\lvert z \rvert = \sqrt{a^2 + b^2}$	Absolute value, Modulus
$arg(z) = tan^{-1}(b/a) = \theta$	Argument
$z\bar{z} = \lvert z \rvert^2$	Modulus squared
$e^{i\theta} = cos(\theta) + i\,sin(\theta)$	Euler's Formula
$z = \lvert z \rvert[cos(\theta) + i\,sin(\theta)]$	Polar form I
$z = \lvert z \rvert e^{i\theta}$	Polar form II

1.18 Sinusoidal Functions

A	Amplitude
ω	Angular Frequency
ϕ	Phase lag
τ	Time delay
ν	Frequency
P	Period

$$f(t) = A\,cos(\omega\,t - \phi)$$
$$f(t) = A\,cos(\omega\,(t - \tau))$$
$$\tau = \phi/\omega$$
$$\nu = \omega/2\pi$$
$$P = 1/\nu$$

1.19 Sinusoidal Identity

$$a\,cos(\omega\,t) + b\,sin(\omega\,t) = A\,cos(\omega\,t - \phi)$$

$a\,cos(\omega\,t) + b\,sin(\omega\,t)$	Rectangular (Cartesian) form
$A\,cos(\omega\,t - \phi)$	Amplitude-phase form

$$
\begin{aligned}
A &= \sqrt{a^2 + b^2} \\
\phi &= tan^{-1}(b/a) \\
a + bi &= Ae^{i\phi} \\
a &= A\,cos(\phi) \\
b &= A\,sin(\phi)
\end{aligned}
$$

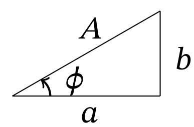

Figure 3: $a + bi = Ae^{i\phi}$

1.20 Line Integral

$$
\begin{aligned}
C &= \vec{r}(t) \\
s &= \text{arc-length}(C) \\
\vec{r}(t) &= \langle x(t), y(t) \rangle \\
P(t) &= M(x, y) \\
Q(t) &= N(x, y)
\end{aligned}
$$

Work

Force on particle along a curve.

$$
\begin{aligned}
\int_C \vec{F} \cdot d\vec{r} &= \int_C \vec{F} \cdot \hat{T}\, ds \\
&= \int_C \langle M, N \rangle \cdot \langle dx, dy \rangle \\
&= \int_C M\,dx + N\,dy \\
&= \int_C (P + Q)\,dt
\end{aligned}
$$

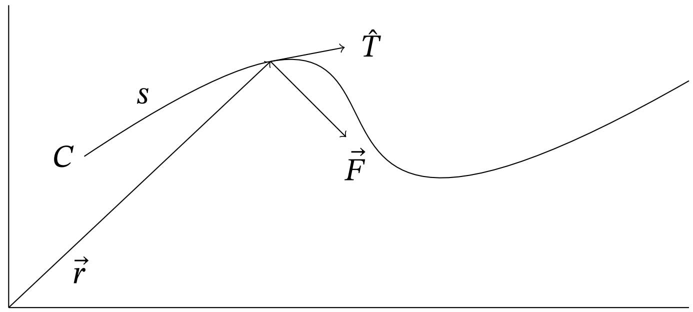

Figure 4: Work

Flow

Flow across a curve.

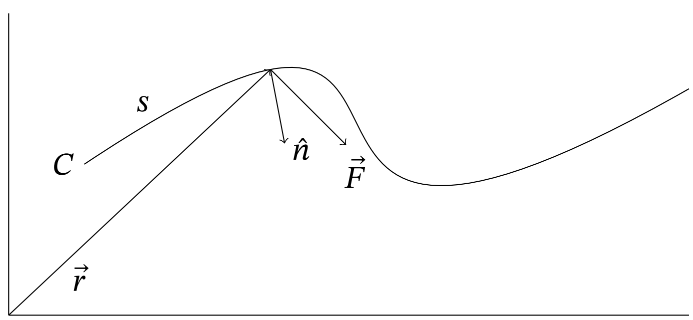

Figure 5: Flow

$$
\begin{aligned}
\int_C \vec{F} \cdot \hat{n}\, ds &= \int_C \langle M, N\rangle \cdot \langle dy, -dx\rangle \\
&= \int_C -N\, dx + M\, dy \\
&= \int_C (P - Q)\, dt
\end{aligned}
$$

Area

Area of a simply connected closed curve.

$$A = \frac{1}{2}\oint_C -y\,dx + x\,dy$$

1.21 Gradient Field

If $\vec{F}(x, y) == \nabla f$ then the field $\vec{F}$ is *conservative*.

$\int_a^b \vec{F} \cdot d\vec{r} = f(b) - f(a)$	Fundamental Theorem for Line Integrals
$\int_{C_1} \vec{F} \cdot d\vec{r} = \int_{C_2} \vec{F} \cdot d\vec{r}$	Path independence
$\oint \vec{F} \cdot d\vec{r} = 0$	If $\vec{r}$ is a closed path

1.22 Green's Theorem

$\oint_C \vec{F} \cdot d\vec{r} = \int\int_R curl(\vec{F})\,dA$	tangental
$\oint_C \vec{F} \cdot \hat{n}\,ds = \int\int_R div(\vec{F})\,dA$	normal

1.23 Differential Equations

Forms

ODE	Homogeneous Solution	Particular Solution	Description
$A(t)\dot{x} + B(t)x = 0$	x_h		Homogeneous ODE
$A(t)\dot{x} + B(t)x = q(t)$		x_p	Inhomogeneous ODE $q(t) \neq 0$
$\dot{x} = ax$	$x(t) = Ce^{at}$		Exponential Growth (Autonomous ODE)
$\dot{x} = f(x) \cdot ax$			Logistic Population Model
$\dot{x} + k\,x = q(t)$	$C\,e^{-kt}$	$e^{-kt}\int e^{kt}q(t)dt$	Constant Coefficient First Order ODE
$\dot{x} + k\,x = B\,e^{at}$	$C\,e^{-kt}$	$\frac{B\,e^{at}}{k+a}$	Exponential Response
$m\,\ddot{x} + k\,x = 0$			Simple Harmonic Oscillator
$m\,\ddot{x} + b\ddot{x} + k\,x = 0$			Damped Harmonic Oscillator

Superposition

If x_1 is a solution to $DE = q_1(t)$ and x_2 is a solution to $DE = q_2(t)$ then for any constants a and b, $a\,x_1 + b\,x_2$ is a solution to $DE = a\,q_1(t) + b\,q_2(t)$.

General Solution

The general solution for a first order ODE is $x_p(t) + c\,x_h(t)$ for any constant c. For an ODE of any order, the number of constants is equal to the order.

Separation of Variables

$$\begin{aligned}\frac{dy}{dx} &= f(x)g(y)\\ \frac{dy}{g(y)} &= f(x)\,dx\\ \int \frac{dy}{g(y)} &= \int f(x)\,dx + c\end{aligned}$$

Integrating Factors

$$\begin{aligned}\frac{dy}{dx} + P(x)y &= Q(x)\\ \frac{d}{dx}(e^{\int P(x)\,dx}\,y) &= Q(x)\,e^{\int P(x)\,dx}\\ \int \frac{d}{dx}(e^{\int P(x)\,dx}\,y) &= \int Q(x)\,e^{\int P(x)\,dx}\\ e^{\int P(x)\,dx}\,y &= \int Q(x)\,e^{\int P(x)\,dx}\\ y &= e^{-\int P(x)\,dx} \int Q(x)\,e^{\int P(x)\,dx}\end{aligned}$$

Differential Operators

$a_n = \text{Constant coefficients}$	
$\sum_{n=0}^{N} a_n\, y^{(n)} = f(t)$	Linear N^{th} order ODE
$\sum_{n=0}^{N} a_n\, D^n = p(D)$	Differential Operator D
$p(D)\, y = f(t)$	Operator form in D
$(p(D) + q(D))y = p(D)y + q(D)y$	Summation
$p(D)(c_1\, f + c_2\, g) = c_1\, p(D)\, f + c_2\, p(D)\, g$	Linearity
$(p(D)\, q(D))y = p(D)\, q(D)y$	Multiplication
$p(D)\, q(D)y = q(D)\, p(D)y$	Multiplication commutes
$p(D)e^{at} = p(a)\, e^{at}$	Substitution
$p(D)e^{at}\, y = e^{at}\, p(D + a)\, y$	Exponential Shift
$p(D)\, y(t - c) = f(t - c)$	Time Invariance

Exponential Response

Particular Solutions

$p(D)\, y = e^{at}$	Exponential Response in operator form
$y = e^{at}/p(a)$	if $p(a) \neq 0$
$y = t\, e^{at}/\dot{p}(a)$	if $p(a) = 0 \wedge \dot{p}(a) \neq 0$
$y = t^2\, e^{at}/\ddot{p}(a)$	if $p(a) = 0 \wedge \dot{p}(a) = 0 \wedge \ddot{p}(a) \neq 0$
$y = t^s\, e^{at}/p^{(s)}(a)$	if $p^{(s-1)..0}(a) = 0 \wedge p^{(s)}(a) \neq 0$

Generalized Characteristic Equation

$$\begin{aligned}
N &= \text{Order of equation} \\
n &= \text{Index of order} \\
M &= \text{Number of distinct roots} \\
m &= \text{Index of first distinct root in } n \text{ space} \\
a_n &= n^{th}\text{ODE constant coefficient} \\
K &= \text{Number of repeated roots} \\
k &= \text{Index of repeated root} \\
r_n &= n^{th} \text{ (sorted) root} \\
c_n &= n^{th} \text{ solution constant} \\
\text{ODE} &= \sum_{n=0}^{N} a_n\, y^{(n)} && \text{Linear } N^{th} \text{ order ODE} \\
\text{CP} &= \sum_{n=0}^{N} a_n r^n && \text{Characteristic Polynomial} \\
r_n &= solve(\text{CP} = 0, r) && \text{Roots of CP} \\
\text{CE} &= \sum_{m=0}^{M} e^{r_m x} \left(\sum_{0}^{K-1} c_{m+k} x^{k-1} \right) && \text{Characteristic Equation}
\end{aligned}$$

Step and Delta Functions

$$\begin{aligned}
u(t) &= (t < 0)\,?\,0 \,:\, 1 && \text{Unit step function} \\
u(t-a) &= (t < a)\,?\,0 \,:\, 1 && \text{Unit step function at } a \\
u(0) &= \frac{1}{2} && \text{Heaviside step function} \\
u_{ab}(t) &= u(t-a) - u(t-b) && \text{Box function } a < t < b \\
\delta(t) &= (t = 0)\,?\,\infty \,:\, 0 && \text{Dirac delta function} \\
f(t)\delta(t) &= f(0)\delta(t) \\
f(t)\delta(t-a) &= f(a)\delta(t) \\
\frac{d}{dt}u(t) &= \delta(t) \\
\int_c^d \delta(t)\, dt &= (c < 0 < d)\,?\,1 \,:\, 0 \\
\int_c^d f(t)\delta(t)\, dt &= (c < 0 < d)\,?\,f(0) \,:\, 0 \\
\int_c^d f(t)\delta(t-a)\, dt &= (c < a < d)\,?\,f(a) \,:\, 0
\end{aligned}$$

Impulse Response

The solution of an impulse response is a homogeneous solution with *almost* rest initial conditions as shown below.

$$
\begin{aligned}
p(D)\,y &= e^{at} && \text{Exponential Response in operator form} \\
y &= e^{at}/p(a) && \text{if } p(a) \neq 0 \\
\sum_{n=0}^{N} a_n\, x^{(n)} &= \delta(t) && && N^{th} \text{ order ODE} \\
x^{(n)}(0) &= 0 && n \neq N-1 && \text{Almost all at rest} \\
x^{(n-1)}(0) &= 1/a_n && n = N-1 && \text{Except for next-to-last}
\end{aligned}
$$

Convolution

$$
\begin{aligned}
f(x) * g(x) &= \int_{0-}^{t+} f(\tau)\, g(t-\tau)\, d\tau && \text{Single Sided} \\
(c_1 f_1 + c_2 f_2) * g &= c_1(f_1 * g) + c_2(f_2 * g) && \text{Distributive} \\
f * g &= g * f && \text{Communitive} \\
f * (g * h) &= (f * g) * h && \text{Associative} \\
\delta(t) * f(t) &= f(t) && \text{Multplicitive identity} \\
\delta(t-a) * f(t) &= f(t-a) && \text{Shift}
\end{aligned}
$$

Green’s Formula

The solution for an arbitrary response is the convolution of the response $f(t)$ with the impulse response $w(t)$.

$$
\begin{aligned}
p(D)\,y &= f(t) && \text{Arbitrary Response in operator form} \\
y &= (f * w)(t) && \text{Solution using convolution}
\end{aligned}
$$

Linearization

$\dot{x} = ax + by$	System 1
$\dot{y} = cx + dy$	System 2
$\begin{pmatrix}\dot{x}\\ \dot{y}\end{pmatrix} = \begin{pmatrix}a & b\\ c & d\end{pmatrix}\begin{pmatrix}x\\ y\end{pmatrix}$	System in matrix form
$A = \begin{pmatrix}a & b\\ c & d\end{pmatrix}$	System coefficients
$\lambda = \lambda_1, \lambda_2$	Eigenvalues
$A\,\mathbf{v} = \lambda\,\mathbf{v}$	Eigenvectors
$\mathbf{a} = \begin{pmatrix}h\\ k\end{pmatrix}$	Solution coefficients
$\dot{\mathbf{x}} = A\,\mathbf{x}$	System in compact form
$\mathbf{x} = e^{\lambda\,t}\,\mathbf{a}$	Solution in compact form
$\lambda^2 - (a+d)\lambda + (ad - bc) = 0$	Characteristic Equation (CE)
$\lambda^2 - tr(A)\lambda + det(A) = 0$	CE with trace and determinant

1.24 Fourier Series

Fourier Coefficients

$$L = \text{half period}$$

$$t = \text{dependent variable, generally time}$$

$$f(t) = \text{given function}$$

$$f(t) = \frac{a_0}{2} + \sum_{n=1}^{\infty} a_n cos(nt) + b_n sin(nt)$$

$$a_0 = \frac{1}{L}\int_{-L}^{L} f(t)\,dt$$

$$a_n = \frac{1}{L}\int_{-L}^{L} f(t)\,cos(n\frac{\pi}{L}t)\,dt$$

$$b_n = \frac{1}{L}\int_{-L}^{L} f(t)\,sin(n\frac{\pi}{L}t)\,dt$$

$$a_n = \frac{2}{L}\int_{0}^{L} f(t)\,cos(n\frac{\pi}{L}t)\,dt \qquad b_0 = 0, f(t) = f(-t), \text{ even function.}$$

$$b_n = \frac{2}{L}\int_{0}^{L} f(t)\,sin(n\frac{\pi}{L}t)\,dt \qquad a_0 = 0, f(-t) = -f(t), \text{ odd function.}$$

1.25 Laplace Transform

Definitions

$F(s) = \int_{0^-}^{\infty} f(t)e^{-st}\,dt = \mathcal{L}(f(t))$	Definition
$a\,f(t) + b\,g(t) = a\,F(s) + b\,G(s)$	Linearity
$e^{zt}f(t) = F(s-z)$	s-shift
$u(t-a)f(t-a) = e^{-as}F(s)$	t-translation I
$u(t-a)f(t) = e^{-as}\mathcal{L}(f(t+a))$	t-translation II
$f'(t) = sF(s) - f(0^-)$	
$f''(t) = s^2F(s) - sf(0^-) - f'(0^-)$	
$f^{(n)}(t) = s^nF(s) - \sum_{k=0}^{n-1} s^{n-k-1} f^{(k)}(0^-)$	
$tf(t) = -F'(s)$	
$t^nf(t) = (-1)^nF^n(s)$	
$(f * g)(t) = F(s)G(s)$	
$\int_{0^-}^{t^+} f(\tau)\,d\tau = \frac{F(s)}{s}$	

Transforms

$1 = \dfrac{1}{s}$	$Re(s) > 0$
$e^{at} = \dfrac{1}{s-a}$	$Re(s) > a$
$t = \dfrac{1}{s^2}$	$Re(s) > 0$
$t^n = \dfrac{n!}{s^{n+1}}$	$Re(s) > 0$
$cos(\omega\, t) = \dfrac{s}{s^2+\omega^2}$	$Re(s) > 0$
$sin(\omega\, t) = \dfrac{\omega}{s^2+\omega^2}$	$Re(s) > 0$
$e^{zt} cos(\omega\, t) = \dfrac{(s-z)}{(s-z)^2+\omega^2}$	$Re(s) > Re(z)$
$e^{zt} sin(\omega\, t) = \dfrac{\omega}{(s-z)^2+\omega^2}$	$Re(s) > Re(z)$
$\delta(t) = 1$	$\forall\, s$
$\delta(t-a) = e^{-as}$	$\forall\, s$
$u(t-a) = e^{-as}/s$	$Re(s) > 0$
$cosh(kt) = \dfrac{s}{s^2-k^2}$	$Re(s) > k$
$sinh(kt) = \dfrac{k}{s^2-k^2}$	$Re(s) > k$
$\dfrac{sin(\omega\, t) - \omega\, t\, cos(\omega\, t)}{2\omega^3} = \dfrac{1}{(s^2+\omega^2)^2}$	$Re(s) > 0$
$\dfrac{t\, sin(\omega\, t)}{2\omega} = \dfrac{s}{(s^2+\omega^2)^2}$	$Re(s) > 0$
$\dfrac{sin(\omega\, t) + \omega\, t\, cos(\omega\, t)}{2\omega} = \dfrac{s^2}{(s^2+\omega^2)^2}$	$Re(s) > 0$
$t^n\, e^{at} = \dfrac{n!}{(s-a)^{n+1}}$	$Re(s) > a$
$\dfrac{1}{\sqrt{\pi\, t}} = \dfrac{1}{\sqrt{s}}$	$Re(s) > 0$
$t^a = \dfrac{\Gamma(a+1)}{s^{a+1}}$	$Re(s) > 0$

Heaviside Coverup

Decomposition of Laplace transforms into partial fractions. Denominator must be distinct linear factors.

$$
\begin{aligned}
G(s) &= \prod_{n=1}^{k} H_n(s) \\
F(s)/G(s) &= \Sigma \frac{A_n}{H_n(s)} \\
D_n(s) &= \frac{G(s)}{H_n(s)} \\
A_n &= \frac{F(s)}{D_n(s)}\bigg|_{solve(s, H_n(s)=0)}
\end{aligned}
$$

2 Science

2.1 Units

Quantity	MKS	Name	Abbrev.
Angle		radian	rad
Solid Angle		steradian	sr
Area	m^2		
Volume	m^3		
Frequency	s^{-1}	Hertz	Hz
Velocity	$m \cdot s^{-1}$		
Acceleration	$m \cdot s^{-2}$		
Angular Velocity	$rad \cdot s^{-1}$		
Angular Acceleration	$rad \cdot s^{-2}$		
Density	$kg \cdot m^{-3}$		
Momentum	$kg \cdot m \cdot s^{-1}$		
Angular Momentum	$kg \cdot m^2 \cdot s^{-1}$		
Force	$kg \cdot m \cdot s^{-2}$	Newton	N
Work, Energy	$kg \cdot m^2 \cdot s^{-2}$	Joule	J
Power	$kg \cdot m^2 \cdot s^{-3}$	Watt	W
Torque	$kg \cdot m^2 \cdot s^{-2}$		
Pressure	$kg \cdot m^{-1} \cdot s^{-2}$	Pascal	Pa

2.2 Lab Reports

Abstract
Objective
Method
Data
Analysis
Conclusion
Bibliography

2.3 Laws

Newton's 1st Law	$\sum \mathbf{F} = 0 \Leftrightarrow \dot{\mathbf{v}}$
Newton's 2nd Law	$\mathbf{F} = m\mathbf{a} = \dot{\mathbf{p}}$
Newton's 3rd Law	$\mathbf{F}_a = -\mathbf{F}_a$
Gravity	$\mathbf{F} = m\mathbf{g}$; $\mathbf{g} = 9.81$ m/s
Hooke's Law	$F_x = -k\Delta x$; $k =$ spring constant
Force	$N = kg \cdot m \cdot s^{-2}$
Energy	$J = N \cdot m$
Power	$W = J \cdot s^{-1}$
Momentum	$\mathbf{p} = m \cdot \mathbf{v}$
Kinetic Energy	$K = \frac{1}{2} m\mathbf{v}^2 = \frac{\mathbf{p}^2}{2m}$
Momentum is conserved	
Energy is conserved	

2.4 Mechanics Problem Workflow

Draw a good picture.
Decorate with forces with a *free body diagram for each body.*
Choose a suitable coordinate system.
Decompose forces on each body.
Determine acceleration for each body.
Determine 1d equations of motion for each body, including necessary constraints.
Reconstruct multidimensional motion vectors.
Algebraically determine kinematics as needed.

3 Engineering

3.1 DC Ohm's Law

$$
\begin{aligned}
I &= \frac{E}{R} &= \frac{P}{E} &= \sqrt{\frac{P}{R}} \\
R &= \frac{E}{I} &= \frac{E^2}{P} &= \frac{P}{I^2} \\
E &= IR &= \frac{P}{I} &= \sqrt{PR} \\
P &= EI &= I^2R &= \frac{E^2}{R}
\end{aligned}
$$

3.2 AC Ohm's Law

$$
\begin{aligned}
I &= \frac{E}{Z} &&= \frac{P}{Ecos(\theta)} &&= \sqrt{\frac{P}{Zcos(\theta)}} \\
Z &= \frac{E}{I} &&= \frac{E^2cos(\theta)}{P} &&= \frac{P}{I^2cos(\theta)} \\
E &= IZ &&= \frac{P}{Icos(\theta)} &&= \sqrt{\frac{PZ}{cos(\theta)}} \\
P &= EIcos(\theta) &&= I^2Zcos(\theta) &&= \frac{E^2cos(\theta)}{Z}
\end{aligned}
$$

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