(1) a) Soluciones (romogéneas: sin (x+\$), cos (x+\$) Condiciones de condorno $y'_1(0) = 0 = y'_1 = \sin x$ $y'_2(1) = 0 = y'_2 = \cos (x - 1)$ A = [p(+)[yz'y, -y, 'yz]] p(+) = 1 $= \left(1 \cdot \left(-\sin(x-i), \sin x - \cos x \cdot \cos(x-i)\right)\right]^{-1}$ = $-\sin^2 x \cos(-i) - \sin(-i) \cos x \sin x$ - $\cos^2 x \cos(-i) + \sin(-i) \cos x \sin x$ $=-\cos(-i)$ $G = \begin{cases} A_{y_2}(x)y_2(t) & 0 \leq x < t \\ A_{y_2}(x)y_1(t) & t \leq x \leq 1 \end{cases}$ $G = -\frac{1}{\cos(-1)} \left[\sin x \cos (t-1) \right] = 0 \leq x \leq t$ $-\frac{1}{\cos(-1)} \cdot \left[\cos(x-1) \sin t\right] + 6 \times 6 \leq 1$ b) Soliciones homogéneas: exp(x), exp(-x) $y_i(-\infty)$ finito $\rightarrow y_i = \exp(x)$ $y_z(+\infty)$ finite $\rightarrow y_z = \exp(-x)$ p(+) = 1 $A = \left[1 \cdot \left(-\exp(-x) \cdot \exp(x) - \exp(x) \cdot \exp(-x)\right)\right]^{-1}$ $G = -\frac{1}{2} \exp(x) \cdot \exp(-t) = -\frac{1}{2} \exp(x - t) - \omega(x < t)$ $-\frac{1}{2} \exp(t-x)$ t Lxton

Problema 3: $g(x,t) = g(\mu+v,t) = g(\mu,t) g(v,t)$ (a) $g(\mu+v,t) = \sum_{n=-\infty}^{\infty} J_n(\mu+v)t^n = g(\mu,t)g(v,t) = \sum_{s=-\infty}^{\infty} J_s(u)t^s \sum_{s=-\infty}^{\infty} J_{s}(v)t^s$ = I I Js(M) Jp(N) + S+P ; healenale m = 5+P $= \sum_{m=-\infty}^{\infty} J_m(u+v) t^m = \sum_{m=-\infty}^{\infty} \sum_{s=-\infty}^{\infty} J_s(u) J_{m-s}(v) t^m$ corrected, $(J_m(u+w) = \sum_{s=m}^{\infty} J_s(u)J_{m-s}(w)$ (b) Escribames el resultado anterior como $J_{m}(\mu+\pi) = \sum_{n=0}^{\infty} J_{s}(\mu) J_{m-s}(\pi) + J_{o}(\mu) J_{m}(\pi) + \sum_{n=0}^{\infty} J_{s}(\mu) J_{m-s}(\pi)$ $J_{o}(\mu+vr) = J_{o}(\mu)J_{o}(rr) + \sum_{s=-\infty}^{-1} J_{s}(\mu)J_{-s}(rr) + \sum_{s=1}^{\infty} J_{s}(\mu)J_{-s}(rr)$ En 12 1º sometoria viscemos el combio 5 -> -5 $\int_{0}^{\infty} J_{0}(\mu + \kappa T) = J_{0}(\mu)J_{0}(\kappa T) + \sum_{i=1}^{\infty} \left(J_{s}(\mu)J_{s}(\kappa T) + J_{s}(\mu)J_{-s}(\kappa T) \right)$ Ya que S∈ Z => J-s(N) = (-1) S J_s(N) ∧ J_s(N) = (-1) S J_s(N) Jo(N+N)= Jo(N) Jo(N) + [(-1) 25 +1 (Jo(N) Jo(N)

更(r) = 1 9 1 (-9) ; 产= enを; 产= -aを HTEO 12-元1 HTEO 12-元1 $\bar{\Phi}(r) = \frac{q}{4\pi\epsilon_0} \left(r^2 + \alpha^2 - 2\alpha r \cos \theta \right)^{-1/2} - \left(r^2 + \alpha^2 - 2\alpha r \cos (\pi - \theta) \right)^2$ $\overline{\Phi}(r) = \frac{9}{4\pi\epsilon_0} \left[(r^2 + \alpha^2 - 2\alpha r \cos \theta)^2 - (r^2 + \alpha^2 + 2\alpha r \cos \theta)^{-1/2} \right]$ $r > \alpha : \overline{g}(r) = \frac{q}{4\pi \epsilon_n} \left[1 - 2 \left(\frac{q}{r} \right) \cos \theta + \left(\frac{\alpha}{r} \right)^2 \right]^2 - r^2 \left[1 - 2 \left(-\frac{q}{r} \right) \cos \theta + \left(-\frac{\alpha}{r} \right)^2 \right]^2$ $\overline{\Phi(r)} = \frac{9}{4\pi \epsilon_0 r} \left[\sqrt{1-2(\frac{9}{4})\cos \theta + (\frac{9}{4})^2} \sqrt{1-2(\frac{9}{4})\cos \theta + (\frac{9}{4})^2} \right]$ * g(x,E)=(1-2x++12)/2= = Pe(x)+e $\frac{J(r) = 9}{4\pi\epsilon_0 r} \cdot 2 \cdot \frac{\sum_{k=0}^{\infty} P_{2k-1}(cose)}{\sum_{k=0}^{\infty} \frac{Q^{2k-1}}{r^{2k-1}}}$ $\Rightarrow \left\langle \frac{d}{dr}(r) = 9 \cdot \sum_{k=0}^{\infty} \frac{Q^{2k-1}}{r^{2k}} \cdot \frac{Q^{2k}}{r^{2k}} \cdot \frac{Q^{2k-1}}{r^{2k}} \cdot \frac{Q^{2k}}{r^{2k}} \cdot$ Para rae = \$\frac{\Para (\cos\theta)}{2716} = \frac{\Para \cos\theta}{2716} \frac{\Para \cos\theta}{2716} \frac{\Para \cos\theta}{2716} (b) Dipolo +>>a; qa= +/2 1 a => 0 $\underline{\Phi}(r) = \underline{q} \left(\underbrace{\alpha P_1(\cos \theta) + \alpha^3 P_3(\cos \theta) + \alpha^5 P_5(\cos \theta) + \dots}_{r,6} \right) = \underline{q} \underbrace{\alpha}_{r,6} \left(\underbrace{P_1(\cos \theta) + \alpha^2 P_3(\cos \theta)}_{r,6} \right) = \underline{q} \underbrace{\alpha}_{r,6} \left(\underbrace{P_2(\cos \theta) + \alpha^2 P_3(\cos \theta)}_{r,6} \right) = \underline{q} \underbrace{\alpha}_{r,6} \left(\underbrace{P_2(\cos \theta) + \alpha^2 P_3(\cos \theta)}_{r,6} \right) = \underline{q} \underbrace{\alpha}_{r,6} \left(\underbrace{P_2(\cos \theta) + \alpha^2 P_3(\cos \theta)}_{r,6} \right) = \underline{q} \underbrace{\alpha}_{r,6} \left(\underbrace{P_2(\cos \theta) + \alpha^2 P_3(\cos \theta)}_{r,6} \right) = \underline{q} \underbrace{\alpha}_{r,6} \left(\underbrace{P_2(\cos \theta) + \alpha^2 P_3(\cos \theta)}_{r,6} \right) = \underline{q} \underbrace{\alpha}_{r,6} \left(\underbrace{P_2(\cos \theta) + \alpha^2 P_3(\cos \theta)}_{r,6} \right) = \underline{q} \underbrace{\alpha}_{r,6} \left(\underbrace{P_2(\cos \theta) + \alpha^2 P_3(\cos \theta)}_{r,6} \right) = \underline{q} \underbrace{\alpha}_{r,6} \left(\underbrace{P_2(\cos \theta) + \alpha^2 P_3(\cos \theta)}_{r,6} \right) = \underline{q} \underbrace{\alpha}_{r,6} \left(\underbrace{P_2(\cos \theta) + \alpha^2 P_3(\cos \theta)}_{r,6} \right) = \underline{q} \underbrace{\alpha}_{r,6} \left(\underbrace{P_2(\cos \theta) + \alpha^2 P_3(\cos \theta)}_{r,6} \right) = \underline{q} \underbrace{\alpha}_{r,6} \left(\underbrace{P_2(\cos \theta) + \alpha^2 P_3(\cos \theta)}_{r,6} \right) = \underline{q} \underbrace{\alpha}_{r,6} \left(\underbrace{P_2(\cos \theta) + \alpha^2 P_3(\cos \theta)}_{r,6} \right) = \underline{q} \underbrace{\alpha}_{r,6} \left(\underbrace{P_2(\cos \theta) + \alpha^2 P_3(\cos \theta)}_{r,6} \right) = \underline{q} \underbrace{\alpha}_{r,6} \left(\underbrace{P_2(\cos \theta) + \alpha^2 P_3(\cos \theta)}_{r,6} \right) = \underline{q} \underbrace{\alpha}_{r,6} \left(\underbrace{P_2(\cos \theta) + \alpha^2 P_3(\cos \theta)}_{r,6} \right) = \underline{q} \underbrace{\alpha}_{r,6} \left(\underbrace{P_2(\cos \theta) + \alpha^2 P_3(\cos \theta)}_{r,6} \right) = \underline{q} \underbrace{\alpha}_{r,6} \left(\underbrace{P_2(\cos \theta) + \alpha^2 P_3(\cos \theta)}_{r,6} \right) = \underline{q} \underbrace{\alpha}_{r,6} \left(\underbrace{P_2(\cos \theta) + \alpha^2 P_3(\cos \theta)}_{r,6} \right) = \underline{q} \underbrace{\alpha}_{r,6} \left(\underbrace{P_2(\cos \theta) + \alpha^2 P_3(\cos \theta)}_{r,6} \right) = \underline{q} \underbrace{\alpha}_{r,6} \left(\underbrace{P_2(\cos \theta) + \alpha^2 P_3(\cos \theta)}_{r,6} \right) = \underline{q} \underbrace{\alpha}_{r,6} \underbrace{\alpha}_{$