Review

Case I:
$$f(x) = (b_m x^m + b_{m-1} x^{m-1} + \dots + b_1 x + b_0) e^{\lambda x}, b_i \in \mathbf{R}.$$

特解可以选取为

$$y^* = x^k (B_m x^m + \dots + B_1 x + B_0) e^{\lambda x}.$$

其中 $B_1,\cdots,B_m\in\mathbf{R},\ k$ 为 L[y]=0 对应特征方程中 λ 的重数。

Case II:
$$f(x) = [\underline{P(x)}\cos\beta x + Q(x)\sin\beta x]e^{\alpha x}, P(x), Q(x) \in \mathbf{R}[x].$$

记 $\max\{\deg P(x),\deg Q(x)\}=n$,,则特解职以选取为 $y^*=x^k\{\overline{A_1(x)}\cos\beta x+B(x)\sin\beta x\}e^{\alpha x}.$

其中 $\deg A(x) = \deg B(x) = n, \ A(x), B(x) \in \mathbf{R}[x], \ k \ \mathsf{h} \ L[y] = 0$ 对应特征方程中 $\lambda = \alpha + \mathrm{i}\beta$ 的重数。

(illusion) Lecture 5 Saturday 29th March, 2025

HW-4

例 1

Lecture 5

Hint: 隐含的初值条件是什么?

$$\Rightarrow V = \lambda + C_1 \otimes \lambda + C_2 \otimes \lambda$$

$$V = \lambda + C_1 \otimes \lambda + C_2 \otimes \lambda$$

=1 f-ix e -ix d (-ix)

C2(4)= 1'Xe 1'X

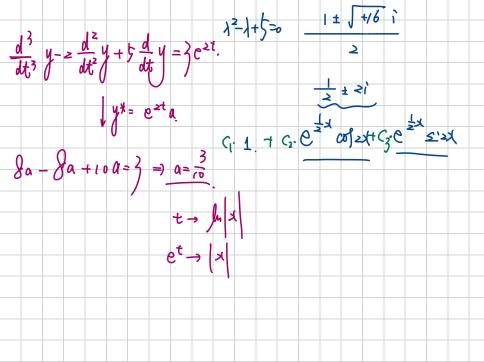
$$y' = 1 - c_1 s_2 + c_2 c_0 s_3$$

$$|x| = 1 + c_2 s_3 + c_2 c_0 s_3$$

$$|x| = 1 + c_2 s_3 + c_2 c_0 s_3 + c_3 = 1 + c_3 + c_4 + c_5 +$$

$$C_{1} = \frac{1}{2} - 1$$

$$2C_{1} \left(-\frac{1}{2} + \frac{1}{2} + \frac{$$



例 3
 给定微分方程

$$\frac{dy}{dx} - xy = xe^{x^2},$$

$$y = f(x)$$

$$y =$$

$$\frac{1}{n^{2}x^{2}+1} = \frac{1}{n^{2}x^{2}+1} = \frac{1}{n^$$

$$\frac{|n|^{N}}{|n|} \ll |\beta| (\beta > 0) \qquad \qquad \frac{|n|^{2} \cdot |n|}{|n|^{2} \cdot |n|} \qquad \Rightarrow 0 (n \rightarrow + 6 \circ)$$

$$\frac{|n|^{N}}{|n|} | (-1 \circ 0 \circ 0) \rightarrow + 0 \circ (+ 1 \rightarrow + 6 \circ)$$

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$$\frac{|n|}{|n|} | (-1 \circ 0 \circ 0) \rightarrow$$

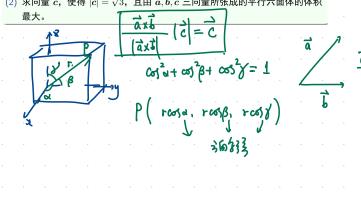
 $\leq \int_{0}^{1} \frac{\sin^{2}x}{h^{2}x^{2}} dx \leq \frac{e}{h} \int_{0}^{1} \frac{1}{h^{2}x^{2}} dx \leq \frac{e}{$

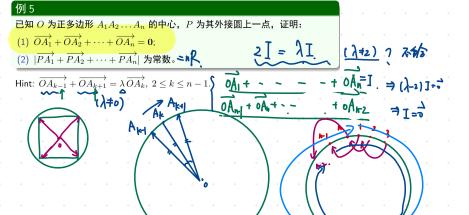
例 4

设右手直角坐标系 $\{O; i, j, k\}$. 给定 a = 2i + 3j - 5k, b = 3i - 4j + k.

(1) 求向量 a 的方向余弦和向量 a 在向量 b 上的投影;

(2) 求向量 c, 使得 $|c| = \sqrt{3}$, 且由 a,b,c 三向量所张成的平行六面体的体积



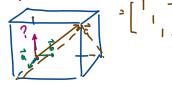


Projection and Schmidt Orthogonalization Process

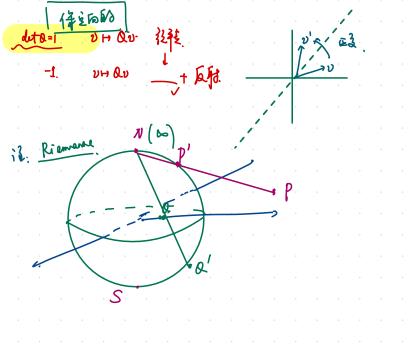
Q: 在空间 $E^3 = (\mathbf{R}^3, \langle \cdot, \cdot \rangle)$ 中有三个不共面的向量 a, b, c,如何操作能让它们 两两正交?

$$e_1 = \frac{a}{|a|}; \quad \text{rest} \quad \underbrace{QQ^{\mathsf{T}} = \mathcal{E}_{\mathbf{1}}}_{\mathbf{1}} \Leftrightarrow \left[\mathbf{e}_1 \ \mathbf{e}_1 \ \mathbf{e}_3 \right] \left[\mathbf{e}_1^{\mathsf{T}} \right] = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1 \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1 & \mathbf{e}_1^{\mathsf{T}} \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1 \\ \mathbf{e}_1^{\mathsf{T}} \end{bmatrix} = \begin{bmatrix} \mathbf{e}_1 \mathbf{e}_1 & \mathbf{e}_1 \\ \mathbf{e}_1 & \mathbf{e}_1 \end{bmatrix}$$

$$oldsymbol{c}' = oldsymbol{c} - rac{oldsymbol{c} \cdot oldsymbol{a}}{|oldsymbol{a}|^2} \ oldsymbol{a} - rac{oldsymbol{c} \cdot oldsymbol{b}'}{|oldsymbol{b}'|^2} \ oldsymbol{b}'
ightsquare oldsymbol{e}_3 = rac{oldsymbol{c}'}{|oldsymbol{c}'|}.$$



- Notes:
 - $Q = [e_1, e_2, e_3]$ 是正交矩阵 \rightarrow 未必右手系,即未必 $\det Q = 1$:
 - ullet QR 分解:设 P 可逆,那么必定存在一个正交矩阵 Q,和一个上三角矩阵 R, 使得 P = QR, 且这种分解是唯一的。



Common Operators On Vectors

给定
$$\boldsymbol{a} = (x_1, y_1, z_1), \boldsymbol{b} = (x_2, y_2, z_2), \boldsymbol{c} = (x_3, y_3, z_3) \in E^3.$$

叉乘(外积,向量积):

- 运算律 I: $(\lambda a) \times b = \lambda(a \times b), a \times b = -b \times a$;
- 运算律 $\parallel : (a+b) \times c = a \times c + b \times c;$

$$\bullet \leadsto \left(\sum_{i=1}^m \lambda_i \boldsymbol{a}_i\right) \times \left(\sum_{j=1}^m \mu_j \boldsymbol{b}_j\right) = \sum_{i=1}^m \sum_{j=1}^m \lambda_i \mu_j (\boldsymbol{a}_i \times \boldsymbol{b}_j);$$

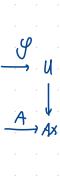
- $a \times b = 0 \Leftrightarrow a // b$;
- $\bullet \ \boldsymbol{a} \times \boldsymbol{b} = \begin{vmatrix} \boldsymbol{i} & \boldsymbol{j} & \boldsymbol{k} \\ x_1 & y_1 & z_1 \\ x_2 & y_2 & z_2 \end{vmatrix}.$



$$(\vec{a} + \vec{b}) \times \vec{C} = \vec{a} \times \vec{C} + \vec{b} \times \vec{C}$$

$$\vec{C} = \vec{A} \times \vec{C} + \vec{b} \times \vec{C}$$

$$\vec{C} = \vec{C} \times \vec{C} = \vec{C}$$
Step $\vec{a} \times \vec{C} = \vec{C}$



• Q: 若 a, b, c 不共面,那么任意 $r \in E^3$ 都有分解

$$r = \frac{(r,b,c)a + (a,r,c)b + (a,b,r)c}{(a|b,c)}$$

$$r = c_1 \vec{a} + c_1 \vec{b} + c_2 \vec{c}$$

$$r = c_1 \vec{a} + c_1 \vec{b} + c_2 \vec{c}$$

$$r = c_1 \vec{a} + c_1 \vec{b} + c_2 \vec{c}$$

$$r = c_1 \vec{a} + c_1 \vec{b} + c_2 \vec{c}$$

$$r = c_1 \vec{a} \cdot (\vec{b} \times \vec{c}) + 0 \Rightarrow c_1 = \frac{(\vec{r}_1 \vec{b}, \vec{c})}{(\vec{a}_1 \vec{b}_1 \vec{c})}$$

$$r_1 = c_1 \vec{a} + c_2 \vec{b} + c_3 \vec{c}$$

$$r_2 = c_1 \vec{a} + c_2 \vec{b} + c_3 \vec{c}$$

$$r_3 = c_1 \vec{a} + c_2 \vec{b} + c_3 \vec{c}$$

$$r_4 = c_1 \vec{a} + c_2 \vec{b} + c_3 \vec{c}$$

$$r_5 = c_1 \vec{a} + c_2 \vec{b} + c_3 \vec{c}$$

$$r_6 = c_1 \vec{a} + c_2 \vec{b} + c_3 \vec{c}$$

$$r_7 = c_1 \vec{a} + c_2 \vec{b} + c_3 \vec{c}$$

$$r_8 = c_1 \vec{a} + c_2 \vec{b} + c_3 \vec{c}$$

$$r_8 = c_1 \vec{a} + c_2 \vec{b} + c_3 \vec{c}$$

13 = x + az + x + x + x + x + x det (a, b, c)

例 6
证明: 对任意的向量
$$a, b, c \in E^3$$
, 有 $b_1 - (b_1c_1 + b_1c_2)a_1$
 $c = (a \times b) \times c = (a \cdot c)b - (b \cdot c)a_1 \cdot a \times (b \times c) = (a \cdot c)b - (a \cdot b)c.$

$$c = (a_1, a_2, a_3) \quad b = (b_1, b_2, b_3) \quad c = (c_1, c_2, c_3)$$

$$\vec{a} \times \vec{b} = \begin{vmatrix} \vec{i} & \vec{j} & \vec{k} \\ a_1 & a_2 & a_3 \\ b_1 & b_2 & b_3 \end{vmatrix} = (a_1b_2 - a_3b_3)\vec{i} + (a_3b_1 - a_1b_3)\vec{j} + (a_1b_2 - a_3b_3)\vec{k}$$

Positional Relationships: Planes

Suppose two planes π_1 and π_2 are given by the equations:

$$\pi_{1}: A_{1}x + B_{1}y + C_{1}z + D_{1} = 0,$$

$$\pi_{2} \text{ i.- } \text{$$