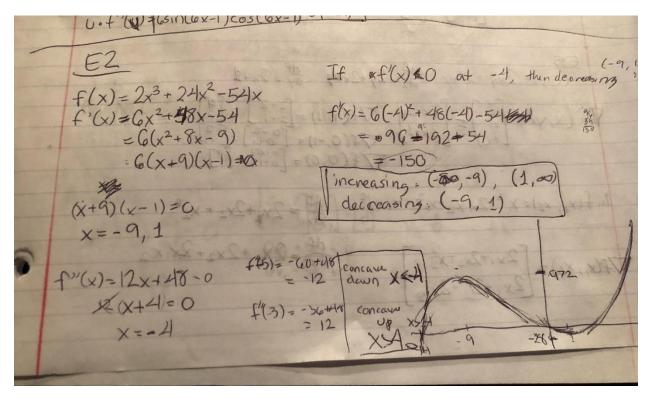
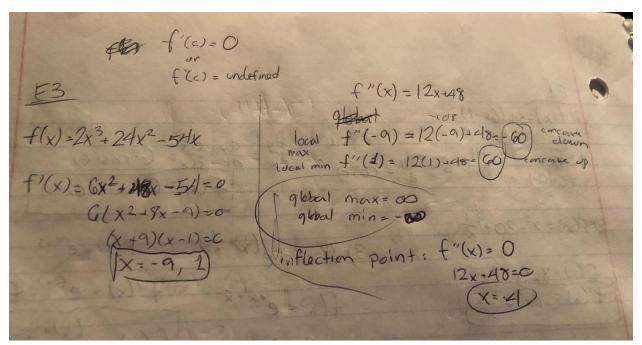
E.1: Practice finding the derivatives of these functions:

E1 (2) = (2)	
$ \frac{1) f(x) = \sin(Gx - 1)}{t} \text{Chain} \\ t = Gx - 1 \frac{dt}{dx} = G \frac{dy}{dt} = \cos(t) \text{Clx} = \frac{dy}{dx} = G \cdot \cos(t) $ $ \frac{1}{t} = Gx - 1 \frac{dy}{dx} = G \cdot \cos(t) $ $ \frac{1}{t} = Gx - 1 \frac{dy}{dx} = G \cdot \cos(t) $	4
2) $f(x) = x^{8} + 30 + x^{4}$ 2) $f(x) = e^{f(x)}$	
$f'(x) = 8x^7 + 1/x^2$ $f(x) = e^{-x^2 + x^2}$	
12 - x ² - 2x ³ 10 - x = (x)	
4) $f(x) = \sin^2(Gx - 1)$ = $(\sin(Gx - 1))^2$ $f(u) = u^2$ $f'(u) = G\cos(Gx - 1)$	
U.f'(w) = (SIN(6x-1) cos(6x-1)=f'(x))	
0.100 1000 1000 1000 1000 1000 1000 100	-9.1

E.2: Finding when a function is increasing/decreasing and concave up/down. When is the function $f(x) = 2x^3 + 24x^2 - 54x$ decreasing? When is it concave up? Plot the function and find your check your answer.

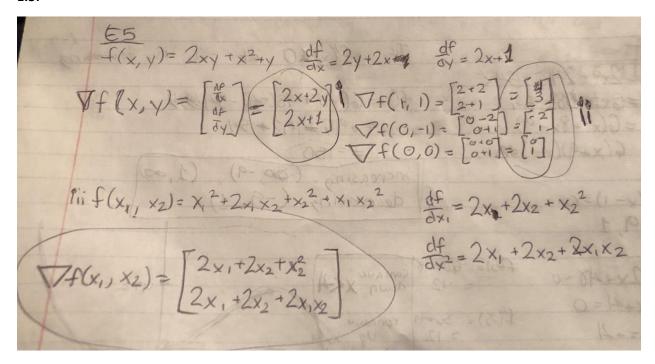


E.3: Finding critical points, local max/min, global max/min, and inflection points. Find all critical points and inflection points of $f(x) = 2x^3 + 24x^2 - 54x$. Classify the critical points as local min, local max, or neither. Find the global max and min of this function on [-3,3] and on $(-\infty,0)$. Plot the function and find your check your answer?

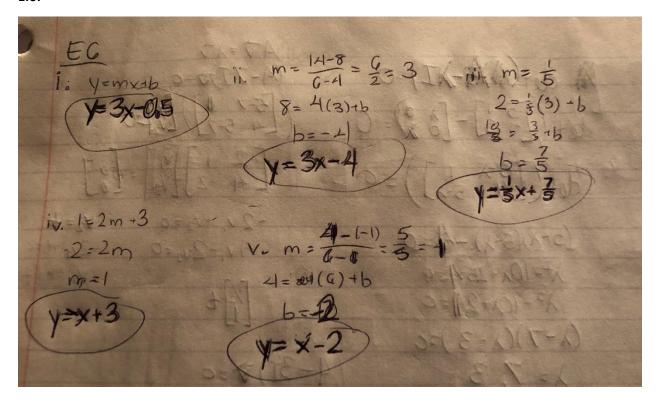


E.4:

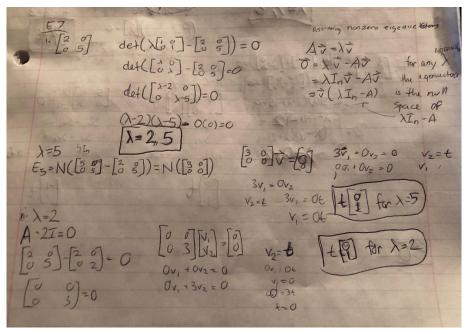
E.5:

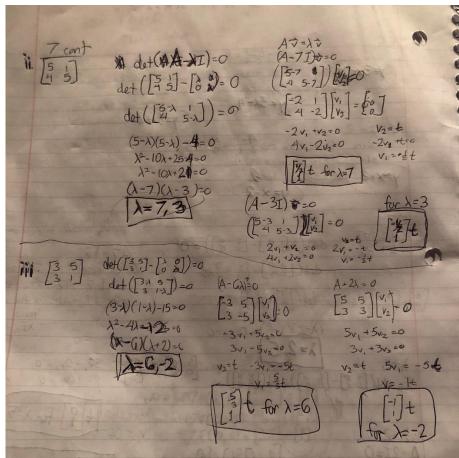


E.6:



E.7: Find the eigenvalues and eigenvectors of the given matrix by hand and check results by the computer (use Python to check your results).

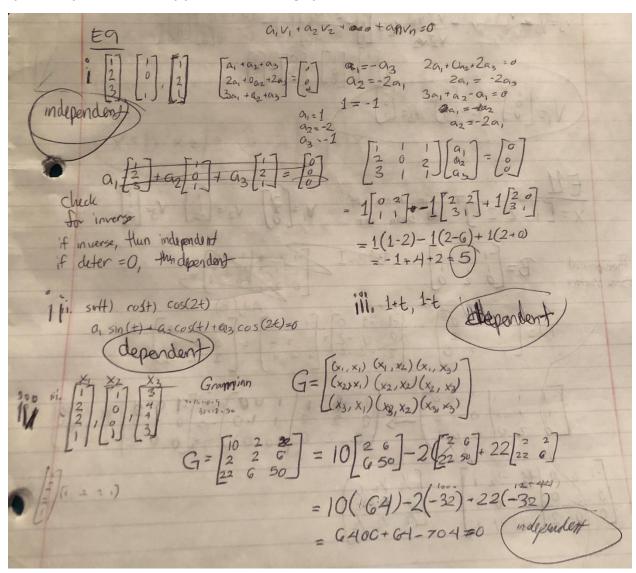




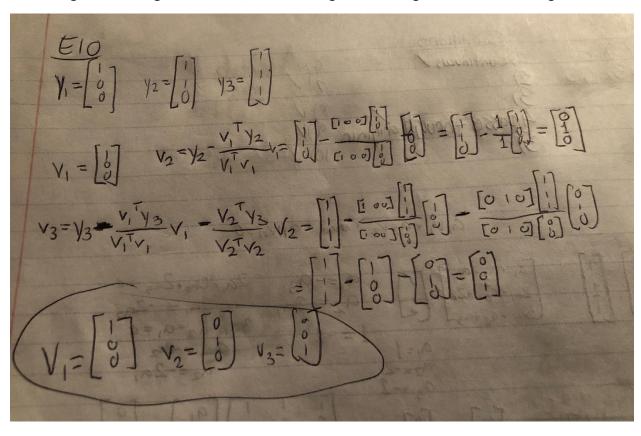
E.8:

	Conditions
i. f(0)=0	1) continuous 7
1 10 3	3)
10	4) passes through anginin oil
1	91

E.9: Which of the following sets of vectors are independent? Find the dimension of the vector space spanned by each set. (Verify your answers using Python).



E.10: Using the following basis vectors, find an orthogonal set using Gram-Schmidt orthogonalization.



E.11: Expand $x = [1 \ 2 \ 2]$ T in terms of the following basis set.

$$B^{\frac{1}{2}} = \begin{bmatrix} \frac{1}{2} & \frac{1}{2} & 0 \\ 0 & 0 & -\frac{1}{2} \\ \frac{1}{2} & \frac{1}{2} \end{bmatrix} \qquad r_{1} = \begin{bmatrix} \frac{1}{2} \\ 0 \\ \frac{1}{2} \end{bmatrix} \qquad r_{2} = \begin{bmatrix} \frac{1}{2} \\ 0 \\ \frac{1}{2} \end{bmatrix} \qquad r_{3} = \begin{bmatrix} \frac{1}{2} \\ \frac{1}{2} \end{bmatrix}$$

$$x_{1} v = \begin{bmatrix} \frac{1}{2} & \frac{1}{2} \\ \frac{1}{2} & \frac{1}{2} \\ \frac{1}{2} & \frac{1}{2} \end{bmatrix} \qquad x_{2} v = r_{2}^{T} x$$

$$x_{1} v = \begin{bmatrix} \frac{1}{2} & \frac{1}{2} \\ \frac{1}{2} & \frac{1}{2} \\ \frac{1}{2} & \frac{1}{2} \end{bmatrix} \qquad x_{3} v = r_{3}^{T} x$$

$$x_{2} v = r_{2}^{T} x$$

$$x_{2} v = r_{2}^{T} x$$

$$x_{3} v = r_{3}^{T} x$$

$$x_{2} v = r_{3}^{T} x$$

$$x_{3} v =$$