

Lab 04 Hand Calculations

Q1 (a) $\frac{dy}{dt} = -\frac{\tan^2 \theta}{y^{1.5}} \frac{d^2}{4} \sqrt{2g}$

(a) for solution up to order error term of h^3

$$y(t+h) = y(t) + hy'(t) + \frac{h^2}{2!} y''(t) + O(h^3)$$

finding the derivatives,

$$y' = \frac{dy}{dt} = -\frac{\tan^2 \theta}{y^{1.5}} \frac{d^2}{4} \sqrt{2g}$$

$$y'' = \frac{d}{dt} \left(\frac{dy}{dt} \right) = -\tan^2 \theta \cdot \frac{d^2}{4} \sqrt{2g} \cdot -1.5 y^{-2.5}$$

$$= \frac{1.5 \tan^2 \theta}{y^{2.5}} \frac{d^2}{4} \sqrt{2g}$$

Hence,

~~$$y(t+h) =$$~~

$$y_{i+1} = y_i + h \left(-\frac{\tan^2 \theta}{y^{1.5}} \frac{d^2}{4} \sqrt{2g} \right) + \frac{h^2}{2!} \left(\frac{1.5 \tan^2 \theta}{y^{2.5}} \frac{d^2}{4} \sqrt{2g} \right) + O(h^3)$$

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Q3. $m \frac{d^2 x}{dt^2} + c \frac{dx}{dt} + kx = 0$

(a) Reducing to system of 1st order ODEs

$$\frac{dx}{dt} = v \rightarrow \textcircled{1}$$

$$\frac{dv}{dt} = -\frac{kx}{m} - \frac{c}{m} v \rightarrow \textcircled{2}$$

(b) Sub $k=0.5$, $c=1.5$, $m=1$ and

$$\frac{d^2x}{dt^2} + 1.5 \frac{dx}{dt} + 0.5x = 0$$

$$x(0) = x_0 = 1.5$$

$$v(0) = 0$$

$$\Delta t = 0.1s$$

$$x_{i+1} = x_i + \frac{h}{6} (k_1 + 2k_2 + 2k_3 + k_4) = f_1(t, x)$$

$$t=0s \rightarrow t=0.1s$$

$$v_{i+1} = v_i + \frac{h}{6} (g_1 + 2g_2 + 2g_3 + g_4) = f_2(t, x, v)$$

$$f_2(t, x, v) = -\frac{k}{m}x - \frac{c}{m}v$$

$$= -0.5x - 1.5v$$

for $i=0$

$$k_1 = f_1(t_0, x_0) \\ = 0$$

$$g_1 = f_2(t_0, x_0, v_0)$$

$$= -\frac{k}{m}x_0 - \frac{c}{m}v_0 = -0.75$$

$$k_2 = f_1(t_0 + \frac{h}{2}, v_0 + \frac{g_1 h}{2}) \\ = 0 + (-0.75) \frac{0.1}{2}$$

$$g_2 = f_2(t_0 + \frac{h}{2}, x_0 + \frac{h k_1}{2}, v_0 + \frac{g_1 h}{2}) \\ = -0.5(1.5 + 0) - 1.5 \left(0 - \frac{0.75 \times 0.1}{2} \right)$$

$$= -0.0375$$

$$= -0.693750$$

$$k_3 = f_1(t_0 + \frac{h}{2}, v_0 + \frac{g_2 h}{2}) \\ = 0 - \frac{0.69375 \times 0.1}{2}$$

$$g_3 = f_2(t_0 + \frac{h}{2}, x_0 + \frac{k_2 h}{2}, v_0 + \frac{g_2 h}{2}) \\ = -0.5 \left(1.5 + \frac{(-0.0375)0.1}{2} \right) - 1.5 \left(\frac{-0.69375 \times 0.1}{2} \right)$$

$$= -0.034688$$

$$= -0.697031$$

$$k_4 = f_1(t_0 + h, v_0 + g_3 h) \\ = 0 + (-0.697031)0.1 \\ = -0.0697031$$

$$g_4 = f_2(t_0 + \frac{h}{2}, x_0 + \frac{k_3 h}{2}, v_0 + \frac{g_3 h}{2})$$

$$= -0.5(1.5 + (-0.034688)0.1)$$

$$- 1.5(-0.697031)0.1$$

$$= -0.643711$$

Substituting $\rightarrow v_{i+1}$ and x_{i+1}

$$x_1 = 1.5 + \frac{0.1}{6} (0 + 2(-0.0375 - 0.034688) - 0.0697031)$$

$$= 1.496432$$

$$z_1 = 0 + \frac{0.1}{6} (-0.75 + 2(-0.69375 - 0.697031) - 0.643711)$$

$$= -0.06958788$$

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Q5

$$\frac{dy}{dt} = -3y + 6e^{-t}$$

$$y(0) = 1.0$$

(a)

$$y_{i+1} = y_i + h(-3y_i) + h(6e^{-t_i})$$

$$y_i^e = y_i + \varepsilon$$

$$y_{i+1}^e = y_i^{(e)} (1-3h)^i \rightarrow (1-3h)^i (y_i^{(e)} + \varepsilon_0)$$

$$(1-3h)^i y_i + \underbrace{(1-3h)^i \varepsilon_0}_{E_t}$$

for $E_t \rightarrow 0$, $i \rightarrow \infty$

$$|1-3h| < 1$$

$$\cancel{-1 < 1-3h < 1} \quad -1 < 1-3h < 1$$

$$-2 < -3h < 0$$

$$\frac{2}{3} > h > 0 \Rightarrow 0 < h < \frac{2}{3}$$

Alternative Method:

(from lecture slides)

$$\frac{dy}{dt} = f(t, y) \leftrightarrow \frac{dy}{dt} = Ky$$

approximated as above,

$$f(t, y) = Ky$$

Chain Rule,

since K is constant

$$\frac{\partial f}{\partial y} = \frac{\partial}{\partial y} (Ky) = \frac{\partial}{\partial y} \cdot K + y \cdot \frac{\partial K}{\partial y}$$

$$\frac{\partial f}{\partial y} = K$$

from equation given, $f(t, y) = \frac{dy}{dt} = -3y + 6e^{-t}$

$$\frac{\partial f}{\partial y} = -3$$

$$\therefore K = -3$$

obtained similar to shown in previous pg
(previous solution)

$$-2 < h \frac{\partial f}{\partial y} < 0$$

$$-2 < hK < 0$$

$$-2 < -3h < 0$$

$$\frac{2}{3} > h > 0$$

$$\Rightarrow 0 < h < \frac{2}{3}$$

(Same as previous method)

(b) $y_{i+1} = y_i + hf(t_{i+1}, y_{i+1})$
 $= y_i + h(Ky_{i+1}) + h(6e^{-t_{i+1}})$

$$y_{i+1} = \left(\frac{1}{1-hK} \right)^i y_i + E_t$$

$$\left(\frac{1}{1-hK} \right)^i \rightarrow 0$$

$$-1 < \frac{1}{1-hK} < 1$$

$$\rightarrow \frac{1}{1-hK} > -1$$

$$-1+hK < 1$$

$$hK < 2$$

$$\frac{1}{1-hK} < 1$$

$$1-hK > 1$$

$$-hK > 0$$

$$hK < 0$$

Sub $K = -3$,

$$h > \frac{2}{3}, h > 0$$

\therefore always stable