

Elements of Maths for Biology

Samuel Bernard^{*}

Laurent Pujo-Menjouet[†]

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^{*}bernard@math.univ-lyon1.fr

[†]pujo@math.univ-lyon1.fr

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1 README

This document is intended to serve both for training and for future reference. As a reference document, you may find it useful for the first biomaths class (3BS, Fall semester) and for linear algebra (3BIM, Winter Semester).

When important concepts are encountered for the first time, they highlighted in **bold** next to their definition. Exercises are important, they can introduce theory or techniques that will be prove useful. We tried to make the examples as complete as possible. This means that they are long, you could probably solve them faster.

2 Fonctions, maps

A **function** is a relation, denoted in general f , that associate an element x belonging to a **domain** I , and at most an element y of the **image** J . The domain I and J are sets, usually $I, J \in \mathbb{R}$.

function
domain
image

A **map** is a relation that associate *each* element of its domain to exactly one element of its image. Maps and functions are related but slightly different concepts. A function f is a map if it is defined for all elements of of its domain I . A map is always a function, but the term can also be used when the domain or the image are not numbers (Figure 1).

map

The **graph** of a function f , denoted $\mathcal{G}(f)$ is the set of all pairs $(x, f(x))$ in the

graph

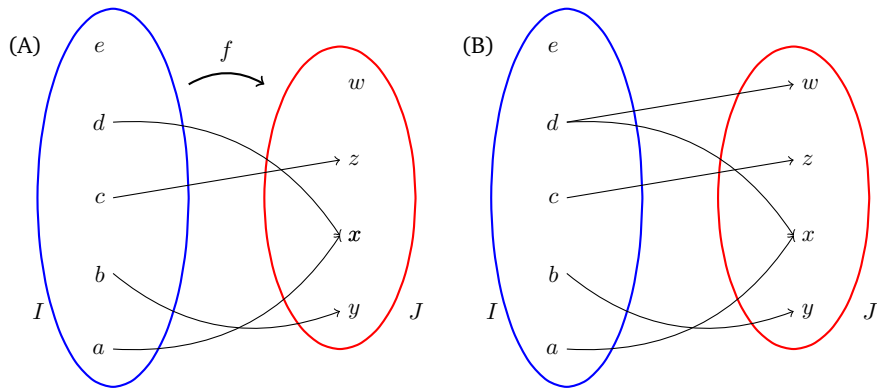


Figure 1: Functions. (A) Function f . (B) Not a function.

$I \times J$ plane. For real-valued functions, the graph is represented in the Cartesian plane.

Functions are not numbers. Do not confuse

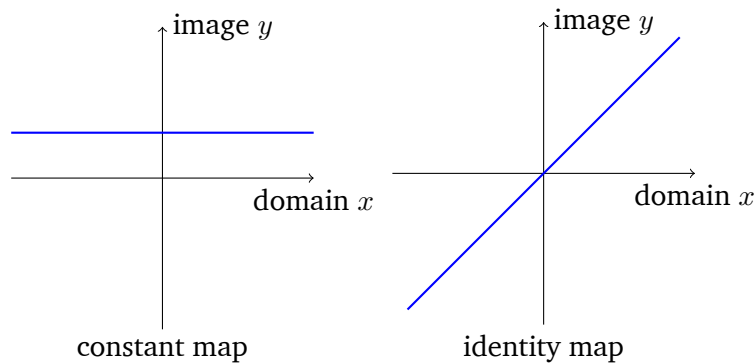
- f the function
- $f(x)$ the evaluation of f at element x ; $f(x)$ is an element of the image (usually a number)
- $\mathcal{G}(f)$ the graph of f .

Consequently, never write

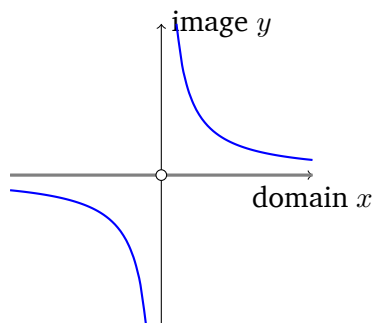
- $f(x)$ is increasing... but write f is increasing...
- $f(x)$ is decreasing... but write f is decreasing...
- $f(x)$ is continuous... but write f continuous...

2.1 Usual maps

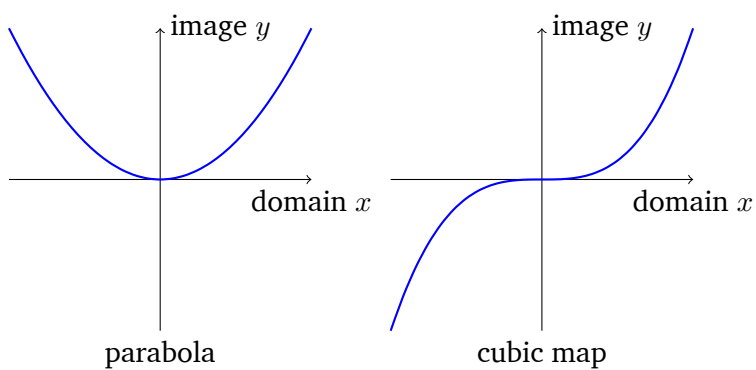
- $f : \mathbb{R} \rightarrow \mathbb{R}$, with $x \rightarrow k$, $k \in \mathbb{R}$ constant; $x \rightarrow x$, identity map.



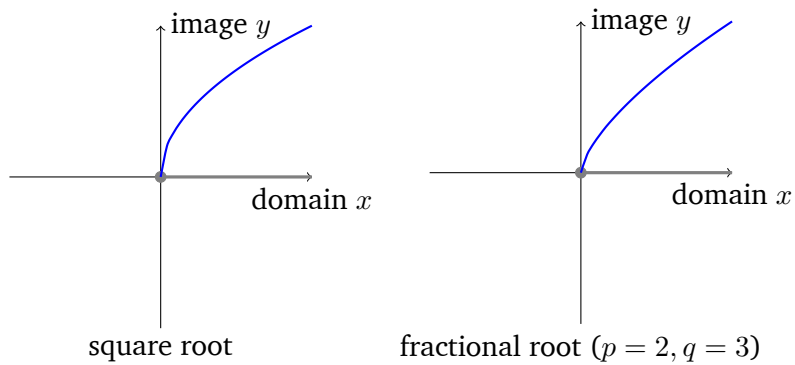
- $f : \mathbb{R} \setminus \{0\} \rightarrow \mathbb{R}$, with $x \rightarrow \frac{1}{x}$, inverse.



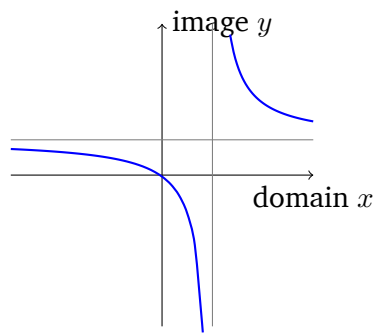
- $f : \mathbb{R} \rightarrow \mathbb{R}$, with $x \rightarrow x^2$, parabola; $x \rightarrow x^3$, cubic map.



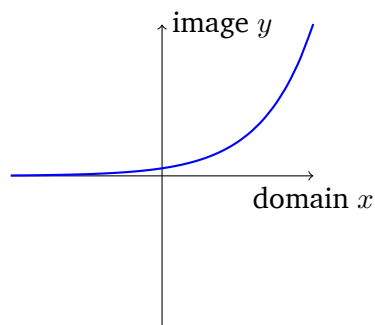
- $f : \mathbb{R}^+ \rightarrow \mathbb{R}$, with $x \rightarrow \sqrt{x} = x^{\frac{1}{2}}$, square root; more generally with $x \rightarrow x^{\frac{p}{q}} = {}^q\sqrt{x^p}$, fractional power.



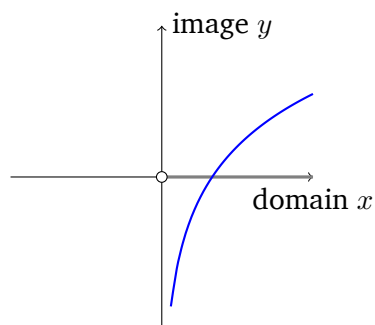
- $f : \mathbb{R} \setminus \{-d/c\} \rightarrow \mathbb{R}$, with $x \rightarrow \frac{ax+b}{cx+d}$.



- $f : \mathbb{R} \rightarrow \mathbb{R}$, with $x \rightarrow \exp(x)$, exponential.

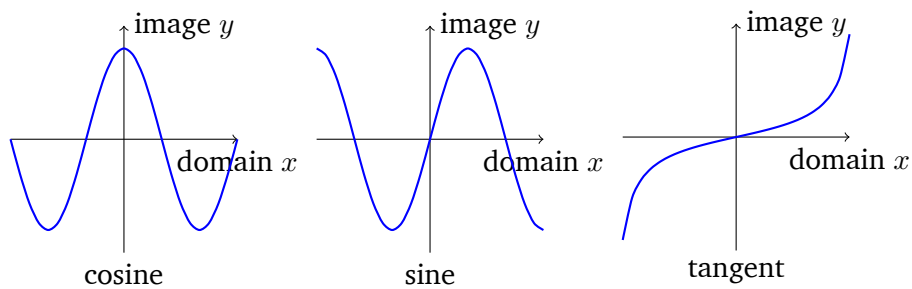


- $f : \mathbb{R}^+ \setminus \{0\} \rightarrow \mathbb{R}$, with $x \rightarrow \ln(x)$, natural logarithm.

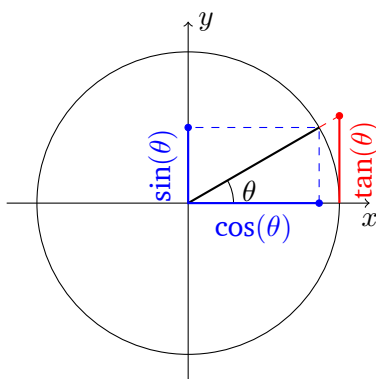


On logarithms: For $a, b > 0$, n positive integer, $\ln(ab) = \ln(a) + \ln(b)$, $\ln(a^n) = n \ln(a)$, $\ln(a/b) = \ln(a) - \ln(b)$.

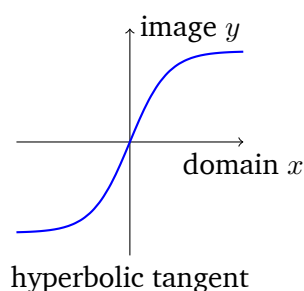
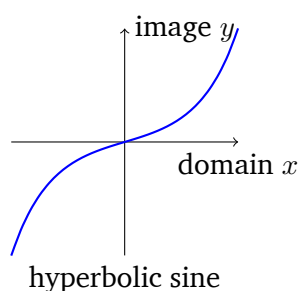
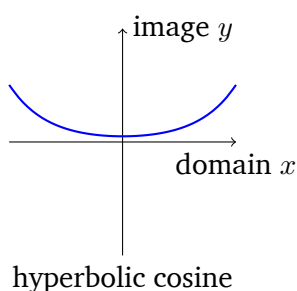
- $f : \mathbb{R} \rightarrow \mathbb{R}$, with $x \rightarrow \cos(x)$, cosine; $x \rightarrow \sin(x)$, sine; $x \rightarrow \tan(x)$, tangent.



On trigonometric functions. In the diagram below is shown the relationship between sine, cosine and tangent, of a angle θ .



- $f : \mathbb{R} \rightarrow \mathbb{R}$, with $x \rightarrow \cosh(x) = \frac{1}{2}(e^x + e^{-x})$, hyperbolic cosine; $x \rightarrow \sinh(x) = \frac{1}{2}(e^x - e^{-x})$, hyperbolic sine; $x \rightarrow \tanh(x) = \frac{\sinh(x)}{\cosh(x)}$, hyperbolic tangent.



2.2 Exercises on functions

3 Derivatives

We call the **derivative** of the function $f : I \rightarrow J$ ($I, J \subset \mathbb{R}$),, at point $a \in I$ the limit, **derivative** if it exists,

$$\lim_{x \rightarrow a} \frac{f(x) - f(a)}{x - a}.$$

The derivative is denoted $f'(a)$. An alternative representation of the limit is obtained by setting $h = x - a$,

$$f'(a) = \lim_{h \rightarrow 0} \frac{f(a + h) - f(a)}{h}.$$

If the derivative exists for all elements $a \in I$, we say that **differentiable** on I .

differentiable

- If f is differentiable on I , and $f'(x) > 0$, then f is strictly increasing on I .
- If f is differentiable on I , and $f'(x) < 0$, then f is strictly decreasing on I .

However, if f is strictly increasing, it does not mean that $f'(x) > 0$. For example

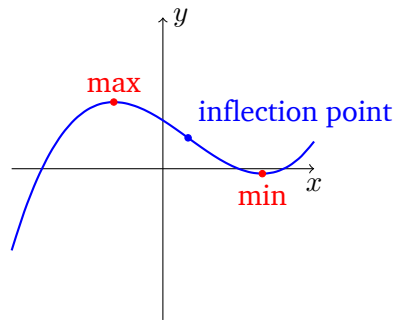


Figure 2: Extrema, inflection points of the polynomial $f(x) = (x + 0.8)(x - 0.5)(x - 0.8)$.

the function f with $f(x) = x^3$ is strictly increasing on \mathbb{R} , but $f'(0) = 0$. Where the derivative exists, we can define the derivative function $f' : I \rightarrow \mathbb{R}$ of f .

The **second derivative** of a function f , denoted f'' is the derivative of f' , where defined. If $f''(x)$ exists and $f''(x) > 0$ for all $x \in I$, we say that f is **convex** (U-shaped). If $f'(x) = 0$ and $f''(x) > 0$, the point x is a **minimum**. If $f'(x)$ and $f''(x) < 0$, the point x is a **maximum**. Maxima and minima are **extrema**. If $f''(0) = 0$, the point x is an **inflection point** (Figure 2).

second
derivative
convex
minimum
maximum
extrema
inflection
point

3.1 List of common derivatives

The derivative is linear. If f and g are differentiable on I , and $a \in \mathbb{R}$,

- $(f + g)' = f' + g'$.
- $(af)' = a(f')$.
- $(af + g)' = a(f') + g'$.

The derivative follow the **rule of composed functions**. If $g : I \rightarrow J$ and $f : J \rightarrow K$, then $f \circ g$ is function $x \rightarrow f(g(x))$. If f and g are differentiable, the derivative

rule of com-
posed func-
tions

$$(f \circ g)'(x) = f'(g(x))g'(x).$$

Example 1 Let $f : x \rightarrow x^2$ and $g : x \rightarrow 3x + 1$, two differentiable functions, with $f'(x) = 2x$ and $g'(x) = 3$. The derivative of the composed function $f \circ g$ at x is

$$f'(g(x))g'(x) = f'(3x + 1)g'(x) = 2(3x + 1) \cdot 3 = 6(3x + 1) = 18x + 6.$$

The derivative could have been obtained by computing the composed function $f(g(x)) = (3x + 1)^2 = 9x^2 + 6x + 1$.

Example 2 Compute the derivative of $f : x \rightarrow \sin(1/x)$. The function f is composed of a sine and an inverse function. To compute the derivative, we decomposed the function f as $f(x) = g(h(x))$ with $g(x) = \sin(x)$ and $h(x) = 1/x$. The derivatives $g'(x) = \cos(x)$ and $h'(x) = -1/x^2$.

$$f'(x) = g'(h(x))h'(x) = \cos(1/x)\left(\frac{-1}{x^2}\right) = -\frac{\cos(1/x)}{x^2}.$$

Example 3 A function f is bijective (invertible) if there exists a function, denoted f^{-1} , such that $f \circ f^{-1} = f^{-1} \circ f$ is the identity map. If f is differentiable and invertible, what is the derivative of f^{-1} ?

We apply the derivative to $f(f^{-1}(x)) = x$ by definition, we have $(f(f^{-1}))' = 1$, and

$$\begin{aligned}(f(f^{-1}))'(x) &= f'(f^{-1}(x))(f^{-1})'(x), \\ &= 1, \\ (f^{-1})'(x) &= \frac{1}{f'(f^{-1}(x))}.\end{aligned}$$

Take for instance $f(x) = x^2$ on $x \in (0, 1]$. The inverse is $f^{-1}(x) = \sqrt{x}$. The derivative of f is $f'(x) = 2x$ and the derivative

$$f^{-1}(x) = \frac{1}{f'(f^{-1}(x))} = \frac{1}{2(\sqrt{x})}.$$

Example 4 Derivative when the independent variable is in the exponent. To compute the derivative of $f : x \rightarrow 2^x$, we need to re-express the function in terms of the natural base e . To do that, we use the properties of the natural logarithm

- For any nonzero expression y , $y = e^{\ln y}$ (\ln is the inverse of the exponential function).
- $\ln(a^b) = b \ln a$.

Then $2^x = e^{\ln(2^x)} = e^{x \ln 2}$. The derivative is $\ln 2 e^{x \ln 2}$. Re-writing in terms of base 2: $\ln 2 2^x$.

Function	Derivative	Note
x^a	ax^{a-1}	$a \in \mathbb{R}$
$\frac{1}{x}$	$-\frac{1}{x^2}$	
$x^{\frac{1}{2}}$	$\frac{1}{2x^{\frac{1}{2}}}$	
$\ln(x)$	$\frac{1}{x}$	
e^x	e^x	
$\cosh(x)$	$\sinh(x)$	
$\sinh(x)$	$\cosh(x)$	
$\cos(x)$	$-\sin(x)$	
$\sin(x)$	$\cos(x)$	
$\tan(x)$	$1 + \tan^2(x) = \frac{1}{\cos^2(x)}$	
$\frac{u(x)}{v(x)}$	$\frac{v(x)u'(x) - u(x)v'(x)}{v^2(x)}$	
$u(x)v(x)$	$u'(x)v(x) + u(x)v'(x)$	

3.2 Exercises on derivatives

Exercise 1 Compute the derivatives of the following functions

- $f_1 : x \rightarrow \sqrt{\cos x}$.
- $f_2 : x \rightarrow \sin(3x + 2)$.
- $f_3 : x \rightarrow e^{\cos x}$.
- $f_4 : x \rightarrow \ln(\sqrt{x})$.
- $f_5 : x \rightarrow 2^{\ln x}$.

4 Taylor series and truncated expansions

If a function f is infinitely differentiable (i.e. $f^{(k)}$ is continuous for any integer $k \geq 0$), the Taylor series of f at point a is the series

$$f(a) + \frac{f'(a)}{1!}(x-a) + \frac{f''(a)}{2!}(x-a)^2 + \frac{f'''(a)}{3!}(x-a)^3 + \dots$$

A function is **analytic** on an open interval I if and only if its Taylor series converges pointwise to the value of the function. Polynomials, exponential and trigonometric function are analytic over all real points. The square root function is not.

The partial sums of the series (or truncated expansion) can be used to approximate a function, and to evaluate it numerically. The k th-order expansion of a function f

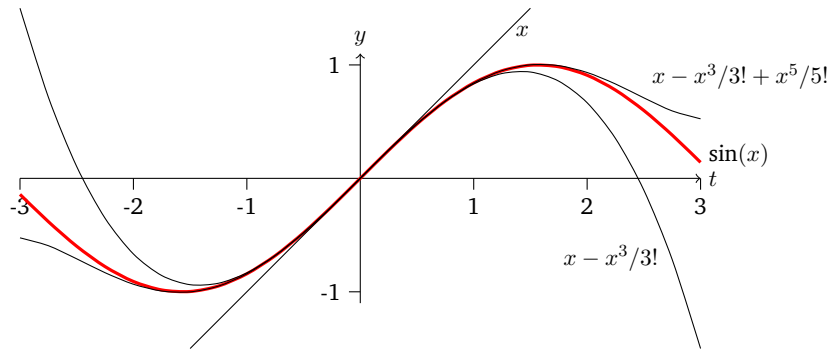


Figure 3: First, third and fifth order expansion of $f(x) = \sin(x)$.

is the polynomial

$$f(a) + \frac{f'(a)}{1!}(x-a) + \frac{f''(a)}{2!}(x-a)^2 + \dots + \frac{f^{(k)}(a)}{k!}(x-a)^k.$$

Example 5 The Taylor series of the sine function at point $a = 0$ is

$$\sum_{n=0}^{\infty} \frac{1}{n!} \frac{d^n \sin(x)}{dx^n} x^n = x - \frac{x^3}{3!} + \frac{x^5}{5!} - \frac{x^7}{7!} + \dots$$

The 3rd-order expansion is the cubic polynomial

$$x - \frac{x^3}{3!}.$$

How good this cubic polynomial approximation to the original sine function? The error is the remainder of the terms of the Taylor series

$$\left| -\frac{x^7}{7!} + \frac{x^9}{9!} - \dots \right|.$$

For $|x| < 1$, the error is bounded by $|x|^7/7!$. Given that $7! = 5040$, the error is less than $1/5040 \approx 0.0002$. Truncated expansions are never good approximations when $|x|$ becomes large, because polynomials are not bounded, but the approximation can be quite good over small intervals around the point at which the Taylor series is computed.

It is important to note that even if a function has a Taylor series, the series may not converge to the function.

Example 6 Let the function

$$f(x) = \begin{cases} 0 & x \leq 0 \\ e^{-\frac{1}{x}} & x > 0. \end{cases}$$

Around 0, all the derivatives exist and are equal to 0. The Taylor series of f at point $x = 0$ is 0, but the function is different from zero.

4.1 Expansion in two variables

For functions of two variables, the Taylor expansion at point $(x_0, y_0)^t \in \mathbb{R}^2$ is

$$\begin{aligned} f(x_0, y_0) = & f(x_0, y_0) + \frac{\partial f(x_0, y_0)}{\partial x}(x - x_0) + \frac{\partial f(x_0, y_0)}{\partial y}(y - y_0) \\ & + \frac{1}{2!} \frac{\partial^2 f(x_0, y_0)}{\partial x^2}(x - x_0)^2 \\ & + \frac{1}{2!} \frac{\partial^2 f(x_0, y_0)}{\partial y^2}(y - y_0)^2 \\ & + \frac{2}{2!} \frac{\partial^2 f(x_0, y_0)}{\partial x \partial y}(x - x_0)(y - y_0) + \dots \end{aligned}$$

Example 7 The second-order truncated expansion of the function $f(x, y) = ye^{-x}$ at $(0, 0)^t$ is

$$y - xy$$

4.2 Expansion of a function from $\mathbb{R}^2 \rightarrow \mathbb{R}^2$

Functions $f : \mathbb{R}^2 \rightarrow \mathbb{R}^2$ have the form

$$f(x, y) = \begin{pmatrix} f_1(x, y) \\ f_2(x, y) \end{pmatrix}.$$

To compute the Taylor series, we need to compute the Taylor series of each function f_1 and f_2 . For a first-order expansion at $(x_0, y_0)^t$, we obtain the expansion

$$\begin{pmatrix} f_1(x_0, y_0) \\ f_2(x_0, y_0) \end{pmatrix} + \begin{pmatrix} \frac{\partial f_1(x_0, y_0)}{\partial x}(x - x_0) + \frac{\partial f_1(x_0, y_0)}{\partial y}(y - y_0) \\ \frac{\partial f_2(x_0, y_0)}{\partial x}(x - x_0) + \frac{\partial f_2(x_0, y_0)}{\partial y}(y - y_0) \end{pmatrix}$$

Using vector notation

$$\mathbf{f}(\mathbf{x}) = \begin{pmatrix} f_1(x, y) \\ f_2(x, y) \end{pmatrix},$$

$$D\mathbf{f} = \begin{pmatrix} \frac{\partial f_1}{\partial x} & \frac{\partial f_1}{\partial y} \\ \frac{\partial f_2}{\partial x} & \frac{\partial f_2}{\partial y} \end{pmatrix},$$

we can write a first-order (or linear) approximation of a function \mathbf{f} compactly

$$\mathbf{f}(\mathbf{x}) \approx \mathbf{f}(\mathbf{a}) + D\mathbf{f}(\mathbf{a})(\mathbf{x} - \mathbf{a}).$$

The approximation is valid only in a neighbourhood of the point \mathbf{a} .

5 Integrals and primitives

5.1 Primitives

Let $f : I \rightarrow \mathbb{R}$, ($I \subset \mathbb{R}$). A **primitive** F of f on I is a differentiable map such that $F'(x) = f(x)$, $x \in I$.

Example 8 If $f(x) = x^2$, we look for $F(x)$ such that $F'(x) = x^2$. Take $F(x) = x^3/3$, then $F'(x) = 3x^2/3 = x^2$. It also work for $F(x) = x^3/3 + C$, for any constant $C \in \mathbb{R}$.

We denote the primitive as $F(x) = \int f(x)dx$. Primitives are unique up to a constant: if F_1 and F_2 are primitives of f , then $F_1'(x) = f(x)$ and $F_2'(x) = f(x)$, which implies that $F_1'(x) - F_2'(x) = 0$. Therefore the difference between F_1 and F_2 , $G : x \rightarrow F_1(x) - F_2(x)$ has a zero derivative: $G'(x) = F_1'(x) - F_2'(x) = 0$. This means that G is a constant.

If F is a primitive of f and G a primitive of g , then $F + G$ is a primitive of $f + g$.

Function	Primitive	Note
0	C	$C \in \mathbb{R}$
a	$ax + C$	$a \in \mathbb{R}$
x^a	$\frac{x^{a+1}}{a+1}$	$a \neq -1$
$x^{-1} = \frac{1}{x}$	$\ln x + C$	$(a = -1), x \neq 0$
e^x	$e^x + C$	
$\cos(x)$	$\sin(x) + C$	
$\sin(x)$	$-\cos(x) + C$	
$f'(g(x))g'(x)$	$f(g(x)) + C$	

Exercise 2 Compute

$$\int \frac{1}{\sqrt{3x+5}} dx$$

5.2 Integrals

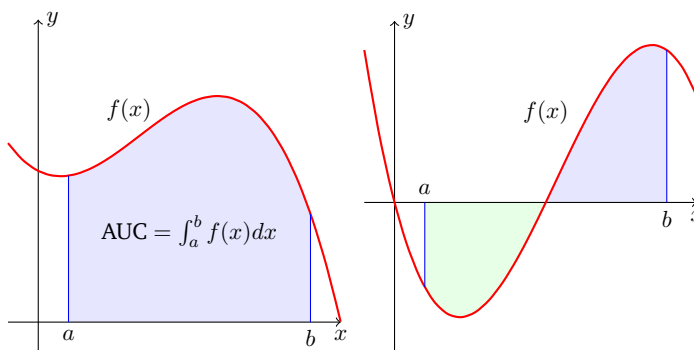
Let $f : [a, b] \rightarrow \mathbb{R}$, and F a primitive of f on $[a, b]$. Then the **definite integral** is the value $F(b) - F(a)$, and is denoted

$$\int_a^b f(x) dx = [F(x)]_a^b.$$

The most important interpretation of the integral is the **area under the curve** (AUC). If $f(x) \geq 0$, $x \in [a, b]$, then

$$\int_a^b f(x) dx$$

is the area under delimited by $f(x)$, x -axis and the axes $x = a$ and $x = b$. Negative values integrate as negative areas.



If f is a rate (unit in something per time), and x is time, then the integral of f has unit something. This applies to speed (integral: displacement), production or degradation (integral: concentration), etc.

The integral has the following properties

- **linearity.** The integral of a sum is the sum of the integrals.

linearity

$$\int_a^b (f(x) + g(x)) dx = \int_a^b f(x) dx + \int_a^b g(x) dx.$$

- **Negative intervals**

$$\int_a^b f(x) dx = - \int_b^a f(x) dx.$$

- Midpoint rule

$$\int_a^b f(x)dx = \int_a^c f(x)dx + \int_c^b f(x)dx.$$

Notice that this works even if c is not between a and b .

- The expression

$$\int_a^x f(t)dt = F(x) - F(a) = F_a(x)$$

is a function of x , and is the primitive of f that takes the value 0 at $x = a$ (remember that a primitive F has an arbitrary constant, so $F(a)$ can be set to any value). Therefore, for any integrable function f

$$\left(\int_a^x f(x)dx \right)' = f(x).$$

This is the **fundamental theorem of calculus**.

fundamental
theorem of
calculus
integration
by parts

- integration by parts

$$\int_a^b f'(x)g(x)dx = f(x)g(x)|_a^b - \int_a^b f(x)g'(x)dx$$

Exercise 3 Compute the integral

$$\int_0^1 xe^x dx$$

Exercise 4 Compute the integral

$$\int_0^\pi \cos x e^x dx$$

Exercise 5 Compute the integral

$$\int_0^1 \sinh x e^x dx$$

6 Differential equations in 1D

An **ordinary differential equation** (ODE) of **order** n is a relation (i.e. an equation) between a real variable $t \in I \subset \mathbb{R}$, an unknown function $x : t \rightarrow x(t)$ and its derivatives $x', x'', x''', \dots, x^{(n)}$ at point t defined by

ordinary
differential
equation
order

$$F(t, x, x', x'', \dots, x^{(n)}) = 0,$$

where F depends on $x^{(n)}$. In general, $x(t)$ takes values in \mathbb{R}^N , i.e. it is a vector. We say that the equation is a **scalar differential equation** if $N = 1$. (The expression $x^{(i)}$ stands for the i -th derivative, not the i -th power.)

scalar differential equation
normal form

The **normal form** of a differential equation of order n is

$$x^{(n)} = f(t, x, x', x'', \dots, x^{(n-1)}).$$

A differential equation is **autonomous** if it does not depend on t , i.e. F has the form

autonomous

$$F(x, x', x'', \dots, x^{(n)}) = 0,$$

A **linear differential equation** is a differential equation for which F is a linear function in $x, x', \dots, x^{(n)}$. It can be expressed as

linear differential equation

$$a_n(t)x^{(n)} + a_{n-1}(t)x^{(n-1)} + \dots + a_1(t)x' + a_0(t)x = g(t),$$

where the coefficients $a_j(t)$ may depend on t , and x and its derivatives $x^{(i)}$ appear only as monomials of degree 1 (that is, linearly). If all coefficients are constants, including g , the linear differential equation is autonomous.

Exercise 6 For the following differential equations, give the order n , and determine whether they are autonomous, linear, and whether they are expressed under their normal form.

1. $x - t + 4tx' = 0$.
2. $(x'')^2 - 2x'tx = 0$.
3. $x^{(3)} + \sin(x') = -5x$.
4. $x^{(4)} - xx' = 0$.
5. $3x'' - 4x' + 6x = 2$.
6. $\ln x' + 3tx = \sqrt{x}$.

A **solution or integral of a differential equation** of order n for t in an interval $I \subset \mathbb{R}$, is a map $x : I \rightarrow \mathbb{R}$ that is n times differentiable for all $t \in I$ and satisfies the differential equation.

solution or integral of a differential equation
integral curve (or chronic)
trajectory or orbit
phase space
phase portrait

A **integral curve (or chronic)** is the set of points $(t, x(t))$ for $t \in I$. If $x(t) \in \mathbb{R}^N$, the integral curve is in \mathbb{R}^{N+1} . A **trajectory or orbit** is the set of points $x(t)$ for $t \in I$. This is a set in \mathbb{R}^N . The space that contains the trajectories is called the **phase space**. The set of all trajectories is called the **phase portrait**.

It is always possible to write an differential equation of order n as a differential equation of order 1, by defining extra variables for the higher-order derivatives.

Example 9 We consider the differential equation $a(t)x'' + b(t)x' + c(t)x = d(t)$. This is a equation of order 2. To reduce it to order 1, let $z_1 = x$ and $z_2 = x'$. Then $x'' = z_2'$ and $z_1' = z_2$. The second-order differential equation can be re-expressed as two first order equations:

$$z_1' = z_2, \quad a(t)z_2' + b(t)z_2 + c(t)z_1 = d(t).$$

Often, the system of first order equations can be re-expressed in normal form, by isolating the variables z_1' and z_2' ,

$$z_1' = z_2, \quad \text{and} \quad z_2' = \frac{d(t) - b(t)z_2 - c(t)z_1}{a(t)}.$$

(We assume that $a(t) \neq 0$.) In general, for the differential equation of order n $F(t, x, x', \dots, x^{(n)}) = 0$, with $x : I \rightarrow \mathbb{R}^m$, we make a change of variables: $z_1 = x$, $z_2 = x'$, ..., $z_i = x^{(i-1)}$ until $z_n = x^{(n-1)}$. Each variable $z_i(t) \in \mathbb{R}^m$, so the new vector $z = (z_1, z_2, \dots, z_n)^t$ is in \mathbb{R}^{mn} . With the change of variables, the differential equation now reads

$$\begin{aligned} z_1' &= z_2, \\ z_2' &= z_3, \\ &\dots, \\ z_i' &= z_{i+1}, \\ &\dots, \\ F(t, z_1, z_2, \dots, z_n, z_n') &= 0. \end{aligned}$$

Tips on Ordinary differential equations

- The most frequently used differential equations are order 1, and they usually are represented in their normal form: $x' = f(x)$ for autonomous equations, and $x' = f(t, x)$ for non-autonomous equations
 - For a scalar, autonomous differential equation $x' = f(x)$ with $x(t) \in \mathbb{R}$, the trajectories are monotonous: if x is a solution, then x is either increasing, decreasing, or constant.
-

6.1 Finding solutions of differential equations

We consider a **first order scalar differential equation**,

first order
scalar dif-
ferential
equation

$$a(t)x' + b(t)x = d(t),$$

$t \in I$ and $a(t) \neq 0$ on I , $a(t)$ and $b(t)$ continuous on I . If $d(t) = 0$, we call the equation homogeneous, and

$$a(t)x' + b(t)x = 0.$$

First order scalar ODE. Homogeneous case, first method. Write the equation in normal form,

$$x' - \frac{b(t)}{a(t)}x.$$

The solution x is either the constant $x = 0$, or $x(t) \neq 0$ for all $t \in I$. We know that because of uniqueness of solutions, which implies that trajectories cannot cross. If $x = 0$ we are done, so we can assume that $x(t) \neq 0$. Dividing the equation by x

$$\frac{x'}{x} = -\frac{b(t)}{a(t)}.$$

The terms on both sides are functions of t . We can compute their primitives

$$\int \frac{x'}{x} dt = - \int \frac{b(t)}{a(t)} dt.$$

The integrand of the left-hand side is x'/x . This is a very common form called **log-derivative** and admit a primitive $\ln|x|$. The right-hand side does not necessarily have a close form, and we leave it as it is. With the integration constant, we have

log-
derivative

$$\ln|x| = - \int \frac{b(t)}{a(t)} dt + K.$$

We would like an explicit solution x ,

$$|x| = e^{- \int \frac{b(t)}{a(t)} dt + K}.$$

Therefore,

$$x = \pm e^K e^{- \int \frac{b(t)}{a(t)} dt}.$$

Notice that t is a variable of integration, and does not exist outside the integral, and can be replaced by any other variable. To have x as a function of t , we must

define the bounds of the integral. When the domain of definition of t is the interval $I = [t_0, t_1]$, $t_0 < t_1$, the solution $x(t)$ is obtained by integrating from t_0 to t ,

$$x = \pm e^K e^{-\int_{t_0}^t \frac{b(u)}{a(u)} du},$$

where we have replaced the variable of integration by u . Then the integral is function of t . The constant K is determined by the **initial condition** on x at t_0 , $x(t_0) = x_0 \in \mathbb{R}$, initial condition

$$x(t_0) = \pm e^K e^{-\int_{t_0}^{t_0} \frac{b(u)}{a(u)} du} = \pm e^K = x_0.$$

The constant $K = \text{sign } x_0 \ln x_0$. The fixed bound at t_0 is arbitrary, we could have chosen any other time of reference. However, it is very common to consider differential equations for which we know the value of the solution at the initial time t_0 . The problem of solving a differential equation with a given initial condition is called **initial value problem (IVP)** or **Cauchy problem**. initial value problem
Cauchy problem

First order scalar ODE. Homogeneous case, second method. Assume that $a(t) \neq 0$, and write the equation as

$$x' + \frac{b(t)}{a(t)}x = 0.$$

Multiply the equation by the term $e^{\int \frac{b(t)}{a(t)} dt}$,

$$x' e^{\int \frac{b(t)}{a(t)} dt} + \frac{b(t)}{a(t)} x e^{\int \frac{b(t)}{a(t)} dt} = 0.$$

Notice that the first term has the form $x' f$ and the second term the form $x f'$, with

$$f = e^{\int \frac{b(t)}{a(t)} dt}.$$

The left-hand-side of the resulting equation, $x' f + x f'$, is the derivative of the product $x f$, so the differential equation can be integrated,

$$x e^{\int \frac{b(t)}{a(t)} dt} = K,$$

$$x = K e^{-\int \frac{b(t)}{a(t)} dt}.$$

The constant K is determined by a condition set on the solution, as in the first method.

Exercise 7 Solve the equation

$$2x' + 6x = 0, \quad x(0) = 1.$$

Exercise 8 Solve the equation

$$x' + \frac{1}{t}x = 0, \quad x(1) = 1.$$

First order scalar ODE. Heterogenous case. We now consider the more general differential equation

$$a(t)x' + b(t)x = d(t).$$

Using the strategy from the second method for the homogeneous case above, we divide the equation by $a(t)$, again assuming that $a(t) \neq 0$, and then multiply by $e^{\int \frac{b(t)}{a(t)} dt}$. The resulting equation now has a non-zero right-hand-side,

$$x'e^{\int \frac{b(t)}{a(t)} dt} + \frac{b(t)}{a(t)}xe^{\int \frac{b(t)}{a(t)} dt} = \frac{d(t)}{a(t)}e^{\int \frac{b(t)}{a(t)} dt}.$$

Nevertheless, the left-hand-side is still of the form $x'f + xf'$, and the right-hand-side only depends on t . By integrating both sides, we obtain

$$xe^{\int \frac{b(t)}{a(t)} dt} = \int \frac{d(t)}{a(t)}e^{\int \frac{b(t)}{a(t)} dt} dt + K.$$

The solution for x is then

$$x = \left(\int \frac{d(t)}{a(t)}e^{\int \frac{b(t)}{a(t)} dt} dt + K \right) e^{-\int \frac{b(t)}{a(t)} dt}.$$

Example 10 We consider the differential equation

$$x' + 3x = 1 + \sin(t), \quad x(0) = x_0 > 0.$$

The coefficients $a(t) = 1, b(t) = 3, d(t) = 1 + \sin(t)$. The term $e^{\int \frac{b(t)}{a(t)} dt} = e^{\int 3dt} = e^{3t}$. The general solution is

$$\begin{aligned} x(t) &= \left(\int (1 + \sin(t))e^{3t} dt + K \right) e^{-3t}, \\ &= \frac{1}{3} + \frac{1}{10}(\sin(t) - \cos(t)) + Ke^{-3t}. \end{aligned}$$

At $t = 0$, the equation $x(0) = \frac{1}{3} + \frac{1}{10}(0 - 1) + K = x_0$ solve in K as $K = x_0 - \frac{7}{30}$. The solution $x(t)$ is

$$x(t) = \frac{1}{3} + \frac{1}{10}(3\sin(t) - \cos(t)) + \left(x_0 - \frac{7}{30}\right)e^{-3t}.$$

We now consider a **nonlinear differential equation of Bernoulli** type. Bernoulli

nonlinear
differential
equation
Bernoulli

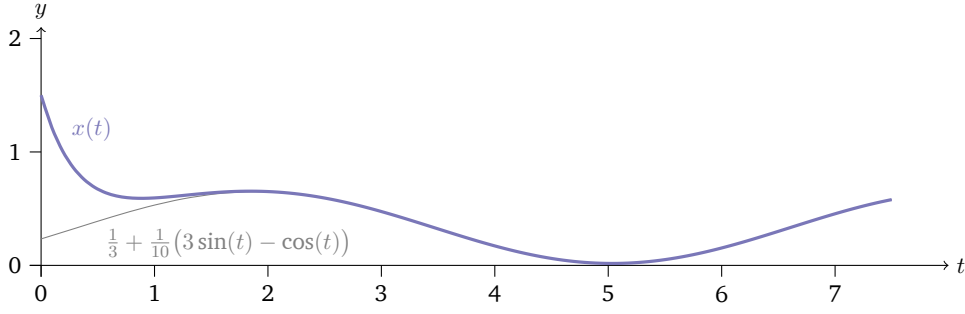


Figure 4: Solution of the initial value problem for the heterogenous differential equation $x' + 3x = 1 + \sin(x)$.

equations are of the form

$$x' + P(t)x + Q(t)x^r = 0, \quad t \in I \subset \mathbb{R},$$

with continuous functions P, Q , and $r \in \mathbb{R}$. There is no general method to solve nonlinear differential equations, but it can be done in particular cases. If $r = 0$ or $r = 1$, the equation is linear, and we already know how to solve it. Suppose r different from 0 or 1. We will look for positive solutions $x(t) > 0$ on $t \in I$. Dividing by x^r , we get

$$\begin{aligned} x'x^{-r} + P(t)xx^{-r} + Q(t)x^rx^{-r} &= 0, \\ x'x^{-r} + P(t)xx^{-r} + Q(t) &= 0. \end{aligned}$$

We now set an auxiliary variable $u = x^{1-r}$, ($x = u^{1/(1-r)}$). Then

$$u' = (1-r)x^{1-r-1}x' = (1-r)x^{-r}x',$$

and, substituting in the differential equation,

$$\begin{aligned} \frac{1}{1-r}u' + P(t)u + Q(t) &= 0, \\ u' + (1-r)P(t)u + (1-r)Q(t) &= 0. \end{aligned}$$

We know how to solve this equation; this is a linear equation of the form

$$a(t)u' + b(t)u = d(t),$$

with $a(t) = 1, b(t) = (1-r)P(t), d(t) = -(1-r)Q(t)$.

Example 11 Verhulst equation (logistic equation)

$$x' = \mu x \left(1 - \frac{x}{K}\right).$$

We first rewrite the equation in Bernoulli form,

$$x' - \mu x + \mu \frac{x^2}{K} = 0,$$

with $P(t) = -1, Q(t) = \mu/K, r = 2$. The auxiliary equation reads

$$u' + (1 - 2)(-1)\mu u + (1 - 2)\frac{\mu}{K} = 0. u' + u - \frac{\mu}{K} = 0.$$

This is a scalar linear equation with $a(t) = 1, b(t) = \mu, d(t) = \mu/K$. The general solution is

$$\begin{aligned} u(t) &= \left(\int \frac{d(t)}{a(t)} e^{\int b(t)/a(t) dt} dt + C \right) e^{-\int b(t)/a(t) dt}, \\ \int b(t)/a(t) dt &= \int \mu dt = \mu t, \\ u(t) &= \left(\int \frac{\mu}{K} e^{\mu t} dt + C \right) e^{-\mu t}, \\ &= \left(\frac{\mu}{K} \frac{e^{\mu t}}{\mu} + C \right) e^{-\mu t}, \\ &= \frac{1}{K} + C e^{-\mu t}. \end{aligned}$$

The initial condition $u(0) = x_0^{1-r} = x_0^{-1}$,

$$\begin{aligned} u(0) &= \frac{1}{K} + C = \frac{1}{x_0}, \\ C &= \frac{1}{x_0} - \frac{1}{K}. \end{aligned}$$

The solution to the original Verhulst equation is $x = u^{-1}$,

$$\begin{aligned} x(t) &= \frac{1}{\frac{1}{K} + \left(\frac{1}{x_0} - \frac{1}{K}\right) e^{-\mu t}} \\ &= \frac{x_0 K}{x_0 + (K - x_0) e^{-\mu t}}. \end{aligned}$$

7 Complex numbers

A complex number is a number that can be expressed in the form $a + ib$, where a and b are real numbers, and the symbol i is called **imaginary unit**. The imaginary unit

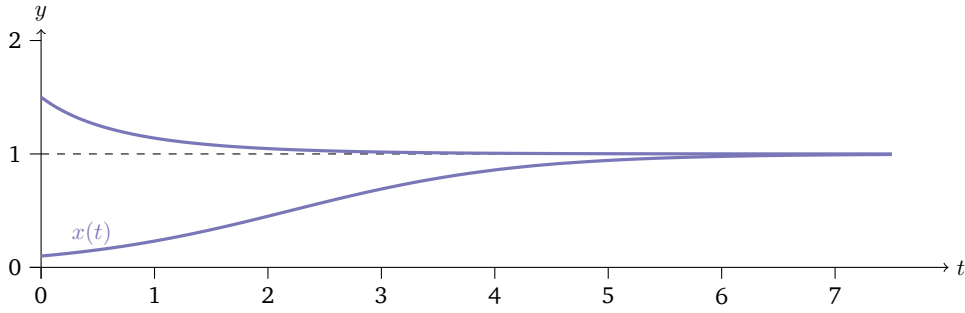


Figure 5: Solution of the initial value problem for the Verhulst equation $x' = \mu x(1 - x/K)$, for $x(0) = 0.1$ and $x(0) = 1.5$. Verhulst equation is a type of Bernoulli equation, and can be solved analytically.

unit satisfies the equation $i^2 = -1$. Because no real number satisfies this equation, this number is called *imaginary*.

For the complex number $z = a + ib$, a is called the **real part** and b is called the **imaginary part**. The real part of z is denoted $\Re(z)$ (`\Re` in LaTeX) or just $\text{Re}(z)$. The imaginary part of z denoted $\Im(z)$ (`\Im` in LaTeX) or just $\text{Im}(z)$. The set of all complex numbers is denoted \mathbb{C} (`\mathbb{C}` in LaTeX).

We need complex numbers for solving polynomial equations. The fundamental theorem of algebra asserts that a polynomial equation of with real or complex coefficients has complex solutions. These polynomial equations arise when trying to compute the eigenvalues of matrices, something we need to do to solve linear differential equations for instance.

Arithmetic rules that apply on real numbers also apply on complex numbers, by using the rule $i^2 = -1$: addition, subtraction, multiplication and division are associative, commutative and distributive.

Let $u = a + ib$ and $v = c + id$ two complex numbers, with real coefficients a, b, c, d . Then

- $u + v = a + ib + c + id = (a + c) + i(b + d)$.
- $uv = (a + ib)(c + id) = ac + iad + ibc + i^2bd = ac - bd + i(ad + bc)$.
- $\frac{1}{v} = \frac{1}{c+id} = \frac{c-id}{(c-id)(c+id)} = \frac{c-id}{c^2+d^2} = \frac{c}{c^2+d^2} - i\frac{d}{c^2+d^2}$.
- $u = v$ if and only if $a = c$ and $b = d$.

It follows from the rule on i that

- $\frac{1}{i} = -i$. (Proof: $\frac{1}{i} = \frac{i}{i^2} = \frac{i}{-1} = -i$.)

Multiplying by the imaginary unit i is equivalent to a counterclockwise rotation by

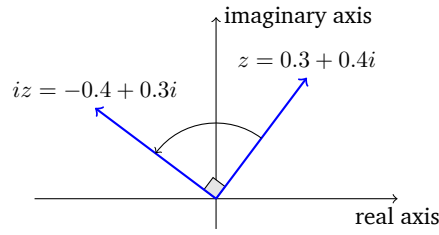


Figure 6: Rotation in the complex plane. Multiplication by i is a 90 degree counter-clockwise rotation.

$\pi/2$ (Figure 6)

$$wi = (a + ib)i = ia + i^2b = -b + ia.$$

Let $z = a + ib$ a complex number with real a and b . The **conjugate** of z , denoted \bar{z} , is $a - ib$. The conjugate of the conjugate of z is z (*reflection*, Figure 6). The **modulus** of z , denoted $|z|$ is $\sqrt{z\bar{z}}$. The product $z\bar{z} = (a+ib)(a-ib) = a^2+b^2+i(-ab+ab) = a^2+b^2$. The modulus is the complex version of the absolute value, for if z (i.e. $b = 0$), $|z| = \sqrt{a^2} = |a|$. It is always a real, positive number, and $|z| = 0$ if and only if $z = 0$. The modulus also has the property of being the *length* of the complex number z , if a and b are the sides of a rectangular triangle, then $|z|$ is the hypotenuse.

When simplifying a ratio involving a complex v at the denominator, it is important to convert it to a real number by multiplying the ratio by \bar{v}/\bar{v} . For instance, if $v \neq 0$,

$$\frac{u}{v} = \frac{u\bar{v}}{v\bar{v}} = \frac{u\bar{v}}{|v|^2}.$$

The denominator $|v|^2$ is always a positive real number.

By allowing complex values, nonlinear functions of real numbers like exponentials, logarithms and trigonometric functions can have their domain extended to all real and complex numbers. The most useful extension is the exponential function. Recall that the exponential function e^x , where $e \approx 2.71828$ is Euler's constant, satisfies the relation $e^{x+y} = e^x e^y$. This remains true for complex numbers. The **Euler's formula** relates the exponential of a imaginary number with trigonometric functions. For a real number y ,

$$e^{iy} = \cos(y) + i \sin(y).$$

Therefore, for any complex number $z = a + ib$, the exponential

$$e^z = e^{a+ib} = e^a e^{ib} = e^a (\cos(b) + i \sin(b)).$$

Tips on complex numbers

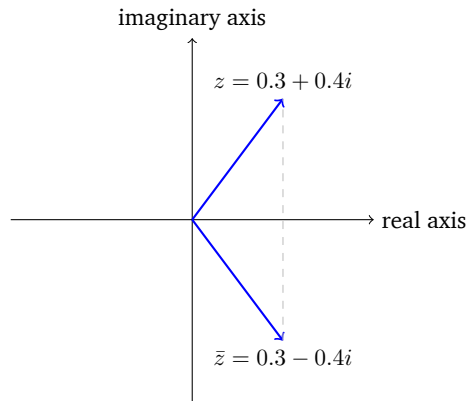


Figure 7: Complex plane

- If x is real, ix is pure imaginary. If y is imaginary, iy is real.
 - $|i| = 1$. For any real θ , $|e^{i\theta}| = 1$.
 - $|z_1 z_2| = |z_1| |z_2|$.
 - In particular, $|iz| = |i| |z| = |z|$. (Multiplying by i is a rotation in the complex plane, it does not change the modulus.)
-

7.1 Roots of a complex number

For complex numbers, the equation $z^n = 1$ has n solutions. They are called the **root of unity**. For $n = 2$, we have the well-known roots $z = \pm 1$, which are real. What are the roots of $z^3 = 1$? To find them, we express z in polar coordinates: $z = re^{i\theta}$. Then

$$z^3 = (re^{i\theta})^3 = r^3 e^{i3\theta} = 1.$$

The equation implies that z has modulus 1, so $r = 1$. The remaining term $e^{i3\theta} = 1$ implies that 3θ is a multiple of 2π because $e^{i\omega} = 1$ if and only if $\omega = 2k\pi$, for some integer k . Therefore $\theta = \frac{2}{3}k\pi$, for $k = 0, 1, 2, \dots$. How many distinct points do we have? Clearly, $k = 3$ is equivalent to $k = 0$: $e^{i\frac{2}{3}3\pi} = e^{i2\pi} = e^{i0}$. In the same way $k = 4$ is equivalent to $k = 1$, and so on. Therefore, there are exactly three distinct solutions for θ : $0, \frac{2}{3}\pi, \frac{4}{3}\pi$ (Figure 8).

7.2 Exercises on complex numbers

Exercise 9 Let the complex number $z = 2 + 3i$. Compute \bar{z} , $|z|$, $|\bar{z}|$ (compare with $|z|$), z^2 , $\Re(\bar{z})$, $\Im(\bar{z})$, $\frac{z+\bar{z}}{2}$, $\frac{z-\bar{z}}{2}$, $-z$, iz .

Exercise 10 Any complex number can be represented in **polar form**: $z = r(\cos(\theta) + i \sin(\theta))$.

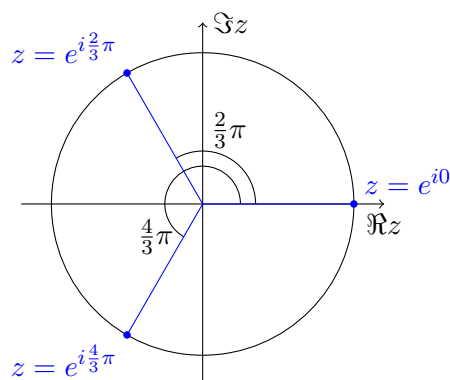


Figure 8: The roots of $z^3 - 1$.

- Show that $|z| = r$
- Show that $z = re^{i\theta}$
- Conclude that for any complex number z , $|z| = 1$ if and only if z can be expressed as $z = e^{i\theta}$ for a real θ .

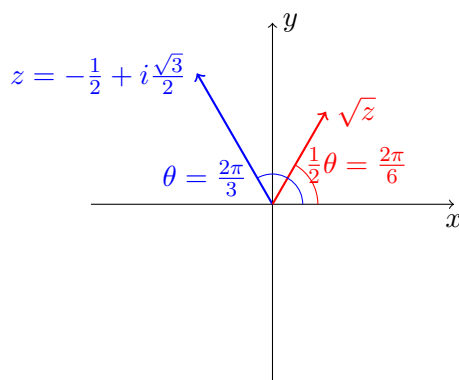
Exercise 11 Using Euler's formula, show that $\cos(a)\cos(b) - \sin(a)\sin(b) = \cos(a+b)$. (Use the property that $e^{ia+ib} = e^{ia}e^{ib}$ and apply Euler's Formula).

Exercise 12 Show Euler's identity: $e^{i\pi} = -1$.

Exercise 13 What are the roots of the equation $z^6 = 1$?

Exercise 14 For a complex z , find necessary and sufficient conditions for e^{zt} , $t > 0$, to converge to 0.

Exercise 15 Let the complex number $z = a + ib$ with real a and b . Compute \sqrt{z} (that is, express $s = \sqrt{z}$ as $s = \alpha + i\beta$, with real α and β)



8 Matrices in dimension 2

8.1 Eigenvalues of a 2×2 matrix

A 2×2 matrix A is an array with 2 rows and 2 columns:

$$A = \begin{pmatrix} a & b \\ c & d \end{pmatrix}.$$

Usually, the **coefficients** a, b, c, d are real numbers. The **identity** matrix is the matrix

coefficients
identity

$$I = \begin{pmatrix} 1 & 0 \\ 0 & 1 \end{pmatrix}.$$

The **determinant** of A , denoted $\det A$ or $|A|$ is the number $ad - bc$. The **trace** of A , denoted $\text{tr } A$, is the sum of the main **diagonal** of A : $a + d$.

determinant
trace
diagonal

The **characteristic polynomial** of A is the second order polynomial in λ obtained by computing the determinant of the matrix $A - \lambda I$ (Figure 9),

characteristic
polynomial

$$\det(A - \lambda I) = (a - \lambda)(d - \lambda) - bc = ad - bc - \lambda(a + d) + \lambda^2.$$

The characteristic polynomial $p_A(\lambda)$ of A can be expressed in terms of its determinant and trace:

$$p_A(\lambda) = \det A - \text{tr } A \lambda + \lambda^2.$$

The **eigenvalues** of A are the roots of the characteristic polynomial. By the fundamental theorem of algebra, we know that the characteristic polynomial has exactly two roots, counting multiple roots. These roots can be real, or complex. The eigenvalues of A are calculated using the quadratic formula:

eigenvalues

$$\lambda_{1,2} = \frac{1}{2} \left(\text{tr } A \pm \sqrt{(\text{tr } A)^2 - 4 \det A} \right).$$

From this formula, we can classify the eigenvalues of A . Let

$$\Delta = (\text{tr } A)^2 - 4 \det A$$

the **discriminant** of the quadratic formula. The two eigenvalues of A are real if and only if $\Delta \geq 0$, i.e. $(\text{tr } A)^2 \geq 4 \det A$. Then we have the following properties (Figure 10):

discriminant

1. $\Delta < 0$, complex eigenvalues

- The two eigenvalues are complex conjugate: $\lambda_1 = \bar{\lambda}_2$

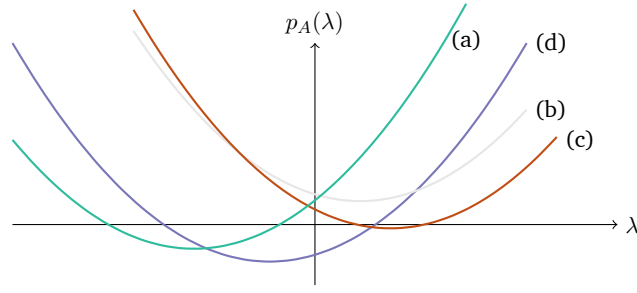


Figure 9: Graph of the characteristic polynomial. (a, green) polynomial with two negative roots, $p(\lambda) = 0.08 + 0.8\lambda + \lambda^2$. (b, gray) polynomial with two complex roots, $p(\lambda) = 0.1 - 0.3\lambda + \lambda^2$. (c, red) polynomial with two positive roots, $p(\lambda) = 0.05 + 0.5\lambda + \lambda^2$. (d, purple) polynomial with a negative and a positive root, $p(\lambda) = -0.1 - 0.3\lambda + \lambda^2$.

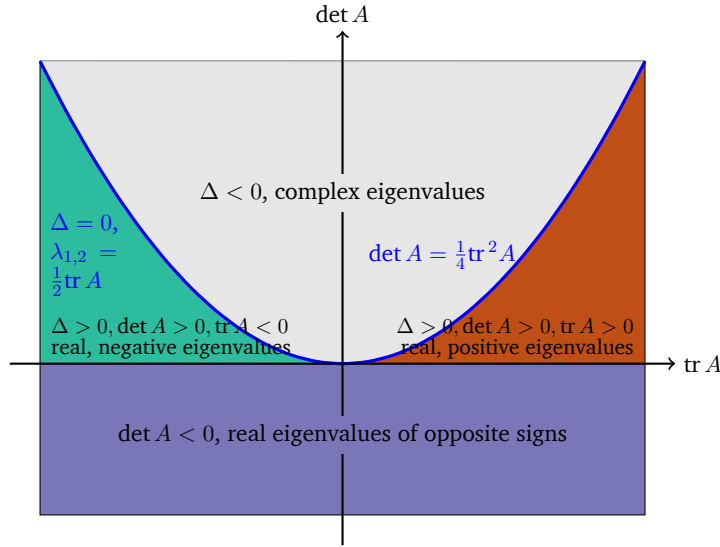


Figure 10: Properties of the eigenvalues of a 2×2 matrix A with respect to $\det A$ and $\text{tr } A$.

- Their real part $\Re(\lambda) = \frac{1}{2}\text{tr } A$.
- 2. $\Delta = 0$, there is a single root of multiplicity 2: $\lambda = \frac{1}{2}\text{tr } A$.
- 3. $\Delta > 0$, $\det A > 0$, real, distinct eigenvalues of the same sign.
 - $\text{tr } A > 0$ and $\det A > 0$. Then $\lambda_{1,2}$ are distinct and positive.
 - $\text{tr } A < 0$ and $\det A > 0$. Then $\lambda_{1,2}$ are distinct and negative.
- 4. $\det A < 0$, real distinct eigenvalues of opposite sign.
 - $\lambda_1 < 0 < \lambda_2$.
- 5. $\det A = 0$ one of the eigenvalue is zero, the other eigenvalue is $\text{tr } A$.

8.1.1 Exercises on eigenvalues

Exercise 16 Properties of the eigenvalues of 2×2 matrices. For each 2×2 matrix, compute the determinant, the trace, and the discriminant, and determine whether the eigenvalues are real, complex, distinct, and the sign (negative, positive, or zero) of the real parts.

$$A_1 = \begin{pmatrix} 0 & -1 \\ 1 & 0 \end{pmatrix}, \quad A_2 = \begin{pmatrix} -2 & 1 \\ 1 & -2 \end{pmatrix}, \quad A_3 = \begin{pmatrix} 1 & -2 \\ 0 & 1 \end{pmatrix}, \quad A_4 = \begin{pmatrix} -1 & 2 \\ 1/2 & 2 \end{pmatrix}.$$

8.2 Matrix-vector operations

A matrix defines a linear transformation between vector spaces. Given a vector x , the product Ax is vector composed of linear combinations of the coefficients of x . For a matrix 2×2 , the vector x must be a vector of size 2, and the product Ax is a vector of size two. If $x = (x_1, x_2)^t$ (the t stands for the transpose, because x must be a column vector), and $A = [a_{ij}]_{i=1,2, j=1,2}$, then

$$Ax = \begin{pmatrix} a_{11} & a_{12} \\ a_{21} & a_{22} \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \end{pmatrix} = \begin{pmatrix} a_{11}x_1 + a_{12}x_2 \\ a_{21}x_1 + a_{22}x_2 \end{pmatrix}.$$

Successive linear transformations can be accomplished by applying several matrices. Given two matrices A, B , the matrix product $C = AB$ is also a matrix. The matrix C is the linear transformation that first applies B , then A . Matrix product is *not* commutative in general: $AB \neq BA$. (If B means 'put on socks' and A means 'put on shoes', then BA does not have the expected result.) The product of two matrices $A = [a_{ij}]_{i=1,2, j=1,2}$ and $B = [b_{ij}]_{i=1,2, j=1,2}$ is

$$AB = \begin{pmatrix} a_{11} & a_{12} \\ a_{21} & a_{22} \end{pmatrix} \begin{pmatrix} b_{11} & b_{12} \\ b_{21} & b_{22} \end{pmatrix} = \begin{pmatrix} a_{11}b_{11} + a_{12}b_{21} & a_{11}b_{12} + a_{12}b_{22} \\ a_{21}b_{11} + a_{22}b_{21} & a_{21}b_{12} + a_{22}b_{22} \end{pmatrix}.$$

The **sum of two matrices** $A + B$ is performed element-wise: $A + B = [a_{ij} + b_{ij}]_{i=1,2, j=1,2}$. The **sum of two vectors** is defined similarly. Addition is commutative. Matrix operations are associative and distributive.

sum of two
matrices
sum of two
vectors

$$\begin{aligned} A + B &= B + A, \\ A(B + C) &= AB + AC, \\ A(BC) &= (AB)C. \end{aligned}$$

Matrices and vectors can be multiplied by a scalar value (real or complex). **Multiplication by a scalar** is associative, distributive, and commutative. The result of the multiplication by a scalar is to multiply each coefficient of the matrix or vector by the scalar. For example, if λ, μ are scalars, Multiplication by a scalar

$$\begin{aligned}\lambda A &= A(\lambda I) = A\lambda, \\ \lambda(A + B) &= \lambda A + \lambda B, \\ (\lambda A)B &= \lambda(AB) = A(\lambda B), \\ (\mu + \lambda)A &= \mu A + \lambda A, \\ \mu(\lambda A) &= (\mu\lambda)A, \dots\end{aligned}$$

The product between two column vectors is not defined, because the sizes do not match. However, we can define the **scalar product** between two column vectors x, y in the same way matrix product is defined: scalar product

$$x^t y \equiv x_1 y_1 + x_2 y_2.$$

If the vectors are complex-valued, we need also to conjugate the transposed vector x^t . The conjugate-transpose is called the **adjoint** and is denoted $*$. Thus, if x is complex-valued, the adjoint x^* is the row vector (\bar{x}_1, \bar{x}_2) . The scalar product for complex-valued vectors is denoted $x^* y$. Since this notation also works for real-valued vector, we will use most of the time. adjoint

Two vectors are **orthogonal** if their scalar product is 0. In the plane, this means that they are oriented at 90 degree apart. Orthogonal vectors are super important because they can be used to build orthogonal bases that are necessary for solving all sorts of *linear problems*. orthogonal

8.2.1 Exercises on Matrix-vector and matrix-matrix operations

Exercise 17 Compute matrix-vector product

$$\begin{pmatrix} 0 & -1 \\ 1 & 0 \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \end{pmatrix}.$$

What is the transformation given by this matrix.

Exercise 18 Compute the matrix-matrix product

$$\begin{pmatrix} 0 & -1 \\ 1 & 0 \end{pmatrix} \begin{pmatrix} 1 & 0 \\ 0 & -1 \end{pmatrix}.$$

Can you tell what transformation this is?

Exercise 19 Now compute the product of the same matrices, but in the inverse order

$$\begin{pmatrix} 1 & 0 \\ 0 & -1 \end{pmatrix} \begin{pmatrix} 0 & -1 \\ 1 & 0 \end{pmatrix}.$$

Compare with the solution found in the previous exercise. What is this transformation?

Exercise 20 Find the matrix that takes a vector $x = (x_1, x_2)^t$ and returns $(ax_1, bx_2)^t$.

Exercise 21 Find the matrix that takes a vector $x = (x_1, x_2)^t$ and returns $(x_2, x_1)^t$.

Exercise 22 Find the matrix that takes a vector $x = (x_1, x_2)^t$ and returns $(x_2, 0)^t$.

Exercise 23 Compute the successive powers A, A^2, A^3, \dots , for a diagonal matrix A :

$$A = \begin{pmatrix} a & 0 \\ 0 & b \end{pmatrix}$$

Exercise 24 Compute the scalar product x^*y between $x = (1 + 2i, 1 - i)^t$ and $y = (0.5 - i, -0.5)^t$.

Exercise 25 Now compute the scalar product y^*x and compare with the result with the previous exercise.

Exercise 26 Compute the scalar product between $z = (z_1, z_2)^t$ and itself, if z is a complex-valued vector. What can you say about the result?

Tips on eigenvalues Some matrices have special shapes that make it easier to compute the determinant, and the eigenvalues. These are called eigenvalue-revealing shapes.

- Diagonal matrices have their eigenvalues on the diagonal.
 - **Triangular matrices**, i.e. matrices that have zeros above (lower-triangular matrix) or below (upper-triangular matrix) the main diagonal have also their eigenvalues on the diagonal. Triangular matrices
 - A matrix with a row or a column of zeros has its determinant equal to zero. This implies that one of its eigenvalues is 0.
-

9 Eigenvalue decomposition

In many applications, it is useful to decompose a matrix into a form that makes it easier to operate complex operations on. For instance, we might want to compute

the powers of a matrix A : A^2, A^3, A^4 . Multiplying matrices are computationally intensive, especially when the size of the matrix becomes large. The **power of a matrix** is $A^k = AA \dots A$, k times. The zeroth power is the identity matrix: $A^0 = I$. power of a matrix

The **inverse** of a matrix A , denoted by A^{-1} is the unique matrix such that $AA^{-1}A^{-1}A = I$. The notation is self-consistent with the positive powers of A . The inverse does not always exist. A matrix is **invertible** if and only if its determinant is not 0. If A and B are invertible, then AB is invertible, and $(AB)^{-1} = B^{-1}A^{-1}$. inverse
invertible

The **eigenvalue decomposition** is a decomposition of the form $A = XDX^{-1}$, where D is a diagonal matrix, and X is an invertible matrix. If there exists such a decomposition for A , then computing powers of A becomes easy: eigenvalue decomposition

$$\begin{aligned} A^k &= (XDX^{-1})^k = XDX^{-1}XDX^{-1} \dots XDX^{-1}, \\ &= XD(X^{-1}X)D(X^{-1}X)D \dots (X^{-1}X)DX^{-1}, \\ &= XD^kX^{-1}. \end{aligned}$$

The eigenvalue decomposition does not always exist, because it is not always possible to find an invertible matrix X . When it exists, though, the columns of the matrix X is composed of the eigenvectors of A . When A is a 2×2 matrix, it is enough to find 2 linearly independent eigenvectors x and y for the matrix

$$X = \left(\begin{array}{c|c} x_1 & y_1 \\ x_2 & y_2 \end{array} \right)$$

to be invertible.

9.1 Eigenvectors

The **eigenvectors** of a matrix A are the *nonzero* vectors x such that for an eigenvalue λ of A , eigenvectors

$$Ax = \lambda x.$$

If x is an eigenvector, so is any αx for any scalar value α . If there are two linearly independent eigenvectors x and y associated to an eigenvalue, $\alpha x + \beta y$ is also an eigenvector. There is at least one eigenvector for each distinct eigenvalue, but there may be more than one when the eigenvalue is repeated.

Example 12 Distinct, real eigenvalues The matrix

$$A = \begin{pmatrix} -1 & -2 \\ 0 & 1 \end{pmatrix}$$

is upper-triangular; this is one of the eigenvalue-revealing shapes. The eigenvalues are -1 and 1 . These are distinct eigenvalues, so each eigenvalue possesses a single eigenvector. The eigenvector x associated to $\lambda_1 = -1$ is found by solving the eigensystem

$$Ax = (-1)x.$$

The unknown quantity x appears on both sides of the equation. We can find a simpler form by noting that multiplying a vector by the identity matrix is neutral: $(-1)x = (-1)Ix$. The eigenproblem becomes

$$\begin{aligned} Ax &= (-1)Ix, \\ Ax - (-1)Ix &= 0, \\ (A - (-1)I)x &= 0, \end{aligned}$$

that is, the eigenvector is a nonzero solution of the linear system $(A - \lambda I)x = 0$. In general, if a matrix B is invertible, the only solution to $Bx = 0$ is $x = 0$ (the vector of zeroes). But, by construction, $A - \lambda I$ cannot be invertible if λ is an eigenvalue: its determinant is exactly the characteristic polynomial evaluated at one of its roots, so it is zero. This is why the eigensystem has nonzero solutions. Now, because $A - \lambda I$ is not invertible, this means that at least one of its rows is a linear combination of the others. For 2×2 matrices, this implies that the two rows are colinear, or redundant. For our example, the eigensystem reads

$$\begin{pmatrix} -1 - (-1) & -2 \\ 0 & 1 - (-1) \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \end{pmatrix} = \begin{pmatrix} 0 \\ 0 \end{pmatrix},$$

$$\begin{pmatrix} 0 & -2 \\ 0 & 2 \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \end{pmatrix} = \begin{pmatrix} 0 \\ 0 \end{pmatrix}.$$

we immediately see that the two rows $(0, -2)$ and $(0, 2)$ are colinear, with a factor -1 . This leads to an underdetermined system: $0x_1 + -2x_2 = 0$. The solution is $x_2 = 0$ and we can take x_1 to be any value, save 0 . We choose $x = (1, 0)^t$.

For the eigenvalue $\lambda_2 = +1$, the eigensystem reads:

$$\begin{pmatrix} -1 - (+1) & -2 \\ 0 & 1 - (+1) \end{pmatrix} \begin{pmatrix} y_1 \\ y_2 \end{pmatrix} = \begin{pmatrix} 0 \\ 0 \end{pmatrix},$$

$$\begin{pmatrix} -2 & -2 \\ 0 & 0 \end{pmatrix} \begin{pmatrix} y_1 \\ y_2 \end{pmatrix} = \begin{pmatrix} 0 \\ 0 \end{pmatrix}.$$

Again, the second row $(0, 0)$ can be neglected, and the solution is $-2y_1 + 2y_2 = 0$, or $y_1 = y_2$. It is customary to choose an eigenvector with norm 1. The **norm** of a complex-valued vector $y = (y_1, y_2)^t$ is

$$\|y\| = \sqrt{y^* y} = \sqrt{\bar{y}_1 y_1 + \bar{y}_2 y_2} = \sqrt{|y_1|^2 + |y_2|^2}.$$

Here, the eigenvector is $y = (y_1, y_1)^t$, so $\|y\| = \sqrt{|y_1|^2 + |y_1|^2} = \sqrt{2}\sqrt{|y_1|^2} = \sqrt{2}|y_1|$. Taking $\|y\| = 1$ solves $|y_1| = 1/\sqrt{2}$. This means that we could take a negative, or a complex value for y_1 , as long as the $|y_1| = 1/\sqrt{2}$. Going for simplicity, we take $y_1 = 1/\sqrt{2}$.

Example 13 Complex eigenvalues

The matrix

$$A = \begin{pmatrix} 0 & -1 \\ 1 & 0 \end{pmatrix}$$

is *not* diagonal, so we have to compute the eigenvalues by hand. The trace of A is zero, the determinant is $0 - (1)(-1) = 1$, and the discriminant is -4 . A negative discriminant implies complex eigenvalues,

$$\lambda_{1,2} = \frac{1}{2}(0 \pm \sqrt{-4}) = \pm i.$$

For the eigenvalue $\lambda_1 = +i$, the eigensystem reads:

$$\begin{pmatrix} -(+i) & -1 \\ 1 & -(+i) \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \end{pmatrix} = \begin{pmatrix} 0 \\ 0 \end{pmatrix},$$

$$\begin{pmatrix} -i & -1 \\ 1 & -i \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \end{pmatrix} = \begin{pmatrix} 0 \\ 0 \end{pmatrix}.$$

The two rows $(-i, 1)$ and $(1, -i)$ should be colinear, but this is not obvious with the complex coefficients. Multiplying the first row by i gives $i(-i, -1) = (-i^2, -i) = (-(-1), -i) = (1, -i)$, the second row, ok. Having confirmed that the system is indeed underdetermined, we can seek a solution to $-ix_1 - x_2 = 0$. Solving for $x_2 =$

$-ix_1$, we obtain the eigenvector $x = (x_1, -ix_2)^t$. Normalization of x imposes

$$||x|| = \sqrt{|x_1|^2 + |-ix_1|^2} = \sqrt{|x_1|^2 + |x_1|^2} = \sqrt{2}|x_1| = 1.$$

As in the previous example, we can choose $x_1 = 1/\sqrt{2}$.

The second eigenvectors, associated $\lambda_2 = -i$, solves the eigensystem

$$\begin{pmatrix} -(-i) & -1 \\ 1 & -(-i) \end{pmatrix} \begin{pmatrix} y_1 \\ y_2 \end{pmatrix} = \begin{pmatrix} 0 \\ 0 \end{pmatrix},$$

$$\begin{pmatrix} i & -1 \\ 1 & i \end{pmatrix} \begin{pmatrix} y_1 \\ y_2 \end{pmatrix} = \begin{pmatrix} 0 \\ 0 \end{pmatrix}.$$

The first row yields $iy_1 - y_2 = 0$, so $y = (y_1, iy_1)^t$. A normalized eigenvector can be $y = (1/\sqrt{2}, i/\sqrt{2})^t$. We could also have chosen $y = (i/\sqrt{2}, -1/\sqrt{2})^t$.

Example 14 Repeated eigenvalues 1

The matrix

$$\begin{pmatrix} -1 & 0 \\ 2 & -1 \end{pmatrix}$$

is lower-triangular, with repeated eigenvalues on the diagonal, $\lambda_{1,2} = -1$. The eigenvectors associated with -1 satisfy the eigenproblem

$$\begin{pmatrix} -1 - (-1) & 0 \\ 2 & -1 - (-1) \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \end{pmatrix} = \begin{pmatrix} 0 \\ 0 \end{pmatrix},$$

$$\begin{pmatrix} 0 & 0 \\ 2 & 0 \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \end{pmatrix} = \begin{pmatrix} 0 \\ 0 \end{pmatrix}.$$

The first row vanishes, and the second row means that $x_1 = 0$, leaving for instance $x_2 = 1$, and $x = (0, 1)^t$. There are no other linearly independent eigenvectors. This is not always the case, repeated eigenvalues can have more than one independent eigenvector, as in the next example.

Example 15 Repeated eigenvalues 2

The matrix

$$\begin{pmatrix} -1 & 0 \\ 0 & -1 \end{pmatrix}$$

is diagonal, with repeated eigenvalues on the diagonal, $\lambda_{1,2} = -1$. The eigenvectors

associated with -1 satisfy the eigenproblem

$$\begin{pmatrix} -1 - (-1) & 0 \\ 0 & -1 - (-1) \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \end{pmatrix} = \begin{pmatrix} 0 \\ 0 \end{pmatrix},$$

$$\begin{pmatrix} 0 & 0 \\ 0 & 0 \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \end{pmatrix} = \begin{pmatrix} 0 \\ 0 \end{pmatrix}.$$

Now, the two rows vanished, leaving no condition at all on x_1 and x_2 . This means that all the vectors are eigenvectors! How many linearly independent eigenvectors can we find? Vectors of size 2 live in a vector space of dimension 2; we can find at most 2 linearly independent vectors. We can choose for instance the canonical basis: $x = (1, 0)^t$ and $y = (0, 1)^t$.

Tips on eigenvalue decomposition

- A 2×2 matrix (or any square matrix) admits an eigenvalue decomposition if all the eigenvalues are distinct. For 2×2 matrices, eigenvalues are distinct if and only if the discriminant $\Delta \neq 0$.
- If the matrix has a repeated eigenvalue, it will admit an eigenvalue decomposition if the number of (linearly independent) eigenvectors is equal to the number of times the eigenvalue is repeated. The number of eigenvectors is called geometric multiplicity, and the number of repeats is called algebraic multiplicity.
- The eigenproblem should be underdetermined; you should always be able to eliminate at least one row by linear combination. If you cannot, this means that there is a error, possibly an incorrect eigenvalue, or a arithmetic mistake in computing $A - \lambda I$.
- Because eigenvalues are in general complex, the eigenvectors will also be complex.
- The eigenvector matrix X needs to be inverted. When the eigenvectors can be chosen so that they are orthogonal and normalized, the inverse $X^{-1} = X^*$ (i.e. the conjugate transpose of X). Symmetric matrices have orthogonal eigenvalues, so this class of matrices are especially easy to diagonalise.
- Eigenvalue decomposition and invertibility are two different concepts. A matrix can be invertible without admitting an eigenvalue decomposition, and vice versa.
- When a matrix does not admit an eigenvalue decomposition, it still can be triangularised. One such triangularisation is the Jordan decomposition: $A =$

$P(D + S)P^{-1}$, where P is invertible, D is the diagonal matrix of eigenvalues, and S is a **nilpotent** matrix, i.e. a nonzero matrix such that $S^k = 0$ for $k \geq k_0 > 1$. **nilpotent**

9.2 Exercises on eigenvalues decomposition

Exercise 27 Find, if there is any, an eigenvalue decomposition of

$$A = \begin{pmatrix} -1 & 2 \\ 2 & -1 \end{pmatrix}$$

To compute X^{-1} , you can use the fact that because A is real and symmetrical, the eigenvectors are orthogonal, meaning that $X^{-1} = X^t$, if the eigenvectors are normalized.

10 Linearisation of functions $\mathbb{R}^2 \rightarrow \mathbb{R}^2$

Nonlinear systems of ordinary differential equations are used to describe the **dynamics** (evolution in time) of concentration of biochemical species, population densities **dynamics** in ecological systems, of the electrophysiology of neurons.

Two dimensional systems are described by two ordinary differential equations (ODEs)

$$\begin{aligned} \frac{dx_1}{dt} &= f_1(x_1, x_2), \\ \frac{dx_2}{dt} &= f_2(x_1, x_2), \end{aligned}$$

The variables x_1, x_2 are functions of time: $x_1(t), x_2(t)$, and f_1, f_2 are the derivatives. We define the two-dimensional vectors $\mathbf{x} = (x_1, x_2)^t$ (here we will use **bold** for vectors), and $\mathbf{f} = (f_1, f_2)^t$. The ODEs can now be represented in vector format,

$$\frac{d\mathbf{x}}{dt} = \mathbf{f}(\mathbf{x}).$$

Here we assume that there exists a point in the 2D plane $\bar{\mathbf{x}}$ such that the derivative $\mathbf{f}(\bar{\mathbf{x}}) = 0$. This point is called a **steady state** because the derivatives are all zeros; **steady state** the steady state is therefore a solution to the system of ODE.

We are interested in how \mathbf{f} is behaving around the steady state. To do that we linearize the function \mathbf{f} at the steady state. **Linearisation** is a first-order expansion. **Linearisation**

For a function from $\mathbb{R}^2 \rightarrow \mathbb{R}^2$, a first-order expansion around a point x_0 is

$$f(x) \approx f(x_0) + Df(x_0)(x - x_0)$$

When expanding around a steady state, the constant term $f(\bar{x}) = 0$. In the second term, Df is a 2×2 matrix, called the Jacobian matrix, and often denoted J . The **Jacobian matrix** for the function f is defined as

Jacobian matrix

$$J = Df = \begin{pmatrix} \frac{\partial f_1}{\partial x_1} & \frac{\partial f_1}{\partial x_2} \\ \frac{\partial f_2}{\partial x_1} & \frac{\partial f_2}{\partial x_2} \end{pmatrix}.$$

When evaluated at a steady state, the Jacobian matrix can provide information on the dynamics of the nonlinear ODE system. More precisely, the eigenvalues of the Jacobian matrix can determine whether the steady state is stable (attracts solutions) or is unstable. **Linearisation around a steady state means computing the Jacobian matrix at the steady state.**

Example 16 Linearisation around a steady state

The Lotka-Volterra equations is a classical ODE system mathematical biology. The equations reads

$$\begin{aligned} \frac{dx}{dt} &= ax - xy, \\ \frac{dy}{dt} &= xy - by, \end{aligned}$$

for a, b positive constants. The solution vector is $x = (x, y)^t$ and the derivatives are $f_1(x, y) = ax - xy$ and $f_2 = xy - by$. We first look for steady states

$$f_1 = ax - xy = 0, \quad f_2 = xy - by.$$

If x and y are not zero, we have $x = b$ and $y = a$. If $x = 0$, the second equation implies $y = 0$. If $y = 0$, the first equation implies $x = 0$. Therefore there are two steady states, $\bar{x} = (b, a)^t$ and $\hat{x} = (0, 0)^t$.

We have the following derivatives

$$\begin{aligned}\frac{\partial f_1}{\partial x}(x, y) &= a - y, \\ \frac{\partial f_1}{\partial y}(x, y) &= -x, \\ \frac{\partial f_2}{\partial x}(x, y) &= y, \\ \frac{\partial f_2}{\partial y}(x, y) &= x - b,\end{aligned}$$

The Jacobian matrix is

$$\mathbf{J} = \begin{pmatrix} a - y & -x \\ y & x - b \end{pmatrix}.$$

Evaluated at the steady state $\bar{\mathbf{x}} = (b, a)^t$ and $\hat{\mathbf{x}} = (0, 0)^t$, the Jacobian matrices are

$$\mathbf{J}(\bar{\mathbf{x}}) = \begin{pmatrix} 0 & -b \\ a & 0 \end{pmatrix}, \quad \mathbf{J}(\hat{\mathbf{x}}) = \begin{pmatrix} a & 0 \\ 0 & -b \end{pmatrix}.$$

10.1 Exercises on linearisation

Exercise 28 Let the function $\mathbf{f} = (f_1, f_2)^t$, with

$$f_1(x, y) = -dx + x \exp(-axy), \quad f_2(x, y) = x - y,$$

$d < 1$, a, d positive. Find the steady states (by solving the equations $f_1 = 0, f_2 = 0$). Compute the Jacobian matrix, and evaluate the Jacobian matrix at each steady state.

Exercise 29 Compute the Jacobian matrices of each of the following functions of (x, y) . All parameters are constants. You do not need to compute the steady states just the matrices.

- van der Pol oscillator

$$f_1(x, y) = \mu((1 - x^2)y - x), \quad f_2(x, y) = y.$$

- Two-compartment pharmacokinetics

$$f_1(x, y) = a - k_{12}x + k_{21}y - k_1x, \quad f_2(x, y) = k_{12}x - k_{21}y.$$

- SI epidemiological model

$$f_1(x, y) = -\beta xy, \quad f_2(x, y) = \beta xy - \gamma y.$$

11 Solution of systems of linear differential equations in dimension 2

Linear differential equations have linear derivative parts, which can be represented in matrix-vector format

$$\frac{d\mathbf{x}(t)}{dt} = \mathbf{A}\mathbf{x}(t),$$

for a vector \mathbf{x} square matrix \mathbf{A} . For initial conditions $\mathbf{x}(t) = \mathbf{x}_0$, the **solution of the linear system of ODEs** is

$$\mathbf{x}(t) = e^{\mathbf{A}t} \mathbf{x}_0.$$

solution of
the linear
system of
ODEs

If we have at our disposal an eigenvalue decomposition of $\mathbf{A} = \mathbf{X}\mathbf{D}\mathbf{X}^{-1}$, the **exponential of the matrix** is

exponential
of the
matrix

$$\begin{aligned} e^{\mathbf{A}t} &= \mathbf{X} e^{\mathbf{D}t} \mathbf{X}^{-1}, \\ &= \mathbf{X} \begin{pmatrix} e^{\lambda_1 t} & 0 \\ 0 & e^{\lambda_2 t} \end{pmatrix} \mathbf{X}^{-1}. \end{aligned}$$

Therefore, the long-time behavior of the exponential is controlled by the eigenvalues $\lambda_{1,2}$.

Example 17 Solution of a linear system of ODEs

Consider the linear system of ODEs given by the Lotka-Volterra model linearised at its nonzero steady state $\bar{\mathbf{x}} = (b, a)^t$ is

$$\begin{pmatrix} \frac{dx}{dt} \\ \frac{dy}{dt} \end{pmatrix} = \begin{pmatrix} 0 & -b \\ a & 0 \end{pmatrix} \begin{pmatrix} x \\ y \end{pmatrix}, \quad \begin{pmatrix} x(0) \\ y(0) \end{pmatrix} = \begin{pmatrix} x_0 \\ y_0 \end{pmatrix}. \quad (1)$$

This system approximates the nonlinear version near the steady state. In this linear system, variables (x, y) are deviations from the steady state; their solutions are "centered" around 0. To solve this linear system, we will diagonalise the matrix

$$\mathbf{A} = \begin{pmatrix} 0 & -b \\ a & 0 \end{pmatrix}.$$

The goal is to go slowly through every step once for this system. In general it is not

necessary to solve the system completely by hand; knowledge of the eigenvalues is often sufficient in many applications.

We have $\det A = 0 - a(-b) = ab > 0$, $\text{tr } A = 0$ and $\Delta = 0 - 4ab = -4ab < 0$. The eigenvalues are therefore complex conjugates: $\lambda_{1,2} = \pm i\sqrt{ab}$. Distinct eigenvalues means that A is diagonalisable. The eigenvector associated to $\lambda_1 = i\sqrt{ab}$ is given by the system

$$\left(\begin{array}{cc|c} -i\sqrt{ab} & -b & 0 \\ a & -i\sqrt{ab} & 0 \end{array} \right)$$

We have from the first row $-i\sqrt{ab}x = by$. Letting $x = b$ and $y = -i\sqrt{ab}$, we obtain the non-normalized eigenvector $\tilde{x}_1 = (b, -i\sqrt{ab})^t$. Normalization is done by dividing by

$$\|\tilde{x}\| = \sqrt{b^2 + (-i\sqrt{ab})^2} = \sqrt{b^2 + ab},$$

to obtain the first eigenvector

$$x = \left(\frac{b}{\sqrt{b^2+ab}}, \frac{-i\sqrt{ab}}{\sqrt{b^2+ab}} \right) = \left(\frac{b}{\sqrt{b}\sqrt{b+a}}, \frac{-i\sqrt{a}\sqrt{b}}{\sqrt{b}\sqrt{b+a}} \right) = \left(\frac{\sqrt{b}}{\sqrt{b+a}}, \frac{-i\sqrt{a}}{\sqrt{b+a}} \right).$$

The second eigenvector is computed the same way (watch out for the slightly different signs!). The eigenproblem for the eigenvalue $\lambda = -i\sqrt{ab}$ is

$$\left(\begin{array}{cc|c} +i\sqrt{ab} & -b & 0 \\ a & +i\sqrt{ab} & 0 \end{array} \right)$$

Given that the only change is $-i \rightarrow +i$, the second eigenvector is

$$x_2 = \left(\frac{\sqrt{b}}{\sqrt{b+a}}, \frac{i\sqrt{a}}{\sqrt{b+a}} \right).$$

The solution to the linear ODE is

$$\begin{pmatrix} x(t) \\ y(t) \end{pmatrix} = \mathbf{X} e^{\mathbf{D}t} \mathbf{X}^{-1} \begin{pmatrix} x_0 \\ y_0 \end{pmatrix},$$

with

$$\mathbf{X} = \frac{1}{\sqrt{b+a}} \begin{pmatrix} \sqrt{b} & \sqrt{b} \\ -i\sqrt{a} & i\sqrt{a} \end{pmatrix}, \quad \mathbf{D} = \begin{pmatrix} +i\sqrt{ab} & 0 \\ 0 & -i\sqrt{ab} \end{pmatrix}$$

The **inverse of a 2×2 matrix** with coefficients a, b, c, d is

inverse of a 2×2 matrix

$$\begin{pmatrix} a & b \\ c & d \end{pmatrix}^{-1} = \frac{1}{ad - bc} \begin{pmatrix} d & -b \\ -c & a \end{pmatrix}.$$

This is conditional to $\det = ad - bc \neq 0$, of course. With this formula, the inverse of \mathbf{X} is

$$\mathbf{X}^{-1} = \frac{1}{\sqrt{b+a}} \frac{1}{\det \mathbf{X}} \begin{pmatrix} i\sqrt{a} & -\sqrt{b} \\ i\sqrt{a} & \sqrt{b} \end{pmatrix}.$$

The determinant $\det \mathbf{X} = \frac{i\sqrt{b}\sqrt{a}}{b+a} + \frac{i\sqrt{a}\sqrt{b}}{b+a} = 2i\frac{\sqrt{ab}}{b+a}$. The inverse reduces to

$$\frac{1}{\sqrt{b+a}} \frac{a+b}{2i\sqrt{ab}} \begin{pmatrix} i\sqrt{a} & -\sqrt{b} \\ i\sqrt{a} & \sqrt{b} \end{pmatrix} = \frac{-i\sqrt{b+a}}{2\sqrt{ab}} \begin{pmatrix} i\sqrt{a} & -\sqrt{b} \\ i\sqrt{a} & \sqrt{b} \end{pmatrix} = \frac{\sqrt{b+a}}{2\sqrt{ab}} \begin{pmatrix} \sqrt{a} & i\sqrt{b} \\ \sqrt{a} & -i\sqrt{b} \end{pmatrix}.$$

We have now obtained the eigenvalue decomposition of $\mathbf{A} = \mathbf{X}\mathbf{D}\mathbf{X}^{-1}$. To solve the linear ODE, we need to compute the product

$$\begin{aligned} \begin{pmatrix} x(t) \\ y(t) \end{pmatrix} &= \mathbf{X}e^{\mathbf{D}t}\mathbf{X}^{-1} \begin{pmatrix} x_0 \\ y_0 \end{pmatrix}, \\ &= \frac{1}{\sqrt{b+a}} \begin{pmatrix} \sqrt{b} & \sqrt{b} \\ -i\sqrt{a} & i\sqrt{a} \end{pmatrix} \begin{pmatrix} e^{+i\sqrt{ab}t} & 0 \\ 0 & e^{-i\sqrt{ab}t} \end{pmatrix} \frac{\sqrt{b+a}}{2\sqrt{ab}} \begin{pmatrix} \sqrt{a} & i\sqrt{b} \\ \sqrt{a} & -i\sqrt{b} \end{pmatrix} \begin{pmatrix} x_0 \\ y_0 \end{pmatrix}, \\ &= \frac{1}{2\sqrt{ab}} \begin{pmatrix} \sqrt{b} & \sqrt{b} \\ -i\sqrt{a} & i\sqrt{a} \end{pmatrix} \begin{pmatrix} e^{+i\sqrt{ab}t} & 0 \\ 0 & e^{-i\sqrt{ab}t} \end{pmatrix} \begin{pmatrix} \sqrt{a} & i\sqrt{b} \\ \sqrt{a} & -i\sqrt{b} \end{pmatrix} \begin{pmatrix} x_0 \\ y_0 \end{pmatrix}, \\ &= \frac{1}{2\sqrt{ab}} \begin{pmatrix} \sqrt{b}e^{+i\sqrt{ab}t} & \sqrt{b}e^{-i\sqrt{ab}t} \\ -i\sqrt{a}e^{+i\sqrt{ab}t} & i\sqrt{a}e^{-i\sqrt{ab}t} \end{pmatrix} \begin{pmatrix} \sqrt{a}x_0 + i\sqrt{b}y_0 \\ \sqrt{a}x_0 - i\sqrt{b}y_0 \end{pmatrix}. \end{aligned}$$

To simplify the last steps of the calculation, we will introduce the following notation. Using Euler's formula, $e^{\pm i\sqrt{ab}t} = \cos(\sqrt{ab}t) \pm i\sin(\sqrt{ab}t)$. Let $c = \cos(\sqrt{ab}t)$, $s =$

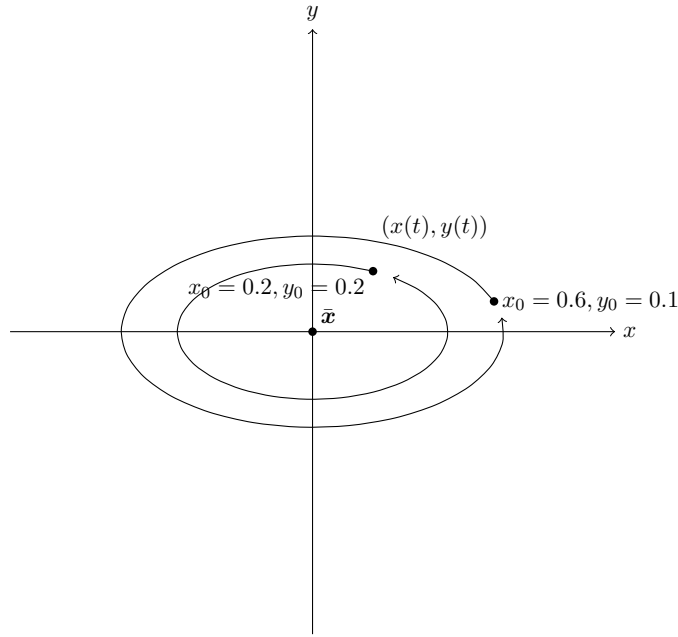


Figure 11: Solution of the linear system of ODEs (1), with $a = 0.1$, $b = 0.4$.

$\sin(\sqrt{abt})$, and $C_1 = \sqrt{a}x_0 + i\sqrt{b}y_0$, $C_2 = \sqrt{a}x_0 - i\sqrt{b}y_0$. The solution reads

$$\begin{aligned}
 \begin{pmatrix} x(t) \\ y(t) \end{pmatrix} &= \frac{1}{2\sqrt{ab}} \begin{pmatrix} \sqrt{b}e^{i\sqrt{abt}}C_1 + \sqrt{b}e^{-i\sqrt{abt}}C_2 \\ -i\sqrt{a}e^{i\sqrt{abt}}C_1 + i\sqrt{a}e^{-i\sqrt{abt}}C_2 \end{pmatrix}, \\
 &= \frac{1}{2\sqrt{ab}} \begin{pmatrix} \sqrt{b}(c + is)C_1 + \sqrt{b}(c - is)C_2 \\ -i\sqrt{a}(c + is)C_1 + i\sqrt{a}(c - is)C_2 \end{pmatrix}, \\
 &= \frac{1}{2\sqrt{ab}} \begin{pmatrix} \sqrt{b}c(C_1 + C_2) + i\sqrt{b}s(C_1 - C_2) \\ \sqrt{a}s(C_1 + C_2) + i\sqrt{a}c(-C_1 + C_2) \end{pmatrix}, \\
 &= \frac{1}{2\sqrt{ab}} \begin{pmatrix} 2\sqrt{ab}\cos(\sqrt{abt})x_0 - 2b\sin(\sqrt{abt})y_0 \\ 2a\sin(\sqrt{abt})x_0 + 2\sqrt{ab}\cos(\sqrt{abt})y_0 \end{pmatrix}, \\
 &= \begin{pmatrix} \cos(\sqrt{abt})x_0 - \sqrt{b/a}\sin(\sqrt{abt})y_0 \\ \sqrt{a/b}\sin(\sqrt{abt})x_0 + \cos(\sqrt{abt})y_0 \end{pmatrix}.
 \end{aligned}$$

And that's it! We have obtained a solution to the linear ODE (Figure 11).

12 Solutions to the exercises

Solution to exercise 1 $f'_1(x) = -\frac{\sin x}{2\sqrt{\cos x}}$. $f'_2(x) = 3\cos(3x+2)$. $f'_3(x) = -\sin(x)e^{\cos x}$.
 $f'_4(x) = \frac{1}{2x}$. $f'_5(x) = \frac{\ln 2}{x}2^{\ln x}$.

Solution to exercise 2 The integrand is the product of two functions, we try inte-

gration by parts. Let $g(x) = x$ and $f'(x) = e^x$. Then $g'(x) = 1$ and $f(x) = e^x$. The integral becomes

$$\begin{aligned}\int_0^1 x e^x dx &= e^x x \Big|_0^1 - \int_0^1 e^x dx, \\ &= e^1 - 0 - e^x \Big|_0^1, \\ &= e - (e^1 - e^0), \\ &= 0 + 1, \\ &= 1.\end{aligned}$$

Solution to exercise 3 The integrand is the product of two functions, we try integration by parts. Let $g(x) = \cos x$ and $f'(x) = e^x$. Then $g'(x) = -\sin x$ and $f(x) = e^x$. The integral becomes

$$\begin{aligned}\int_0^\pi \cos x e^x dx &= e^x (\cos x) \Big|_0^\pi - \int_0^\pi e^x (-\sin x) dx, \\ &= -e^\pi - e^0 - \int_0^\pi e^x (-\sin x) dx, \\ &= -e^\pi - 1 - \int_0^\pi e^x (-\sin x) dx,\end{aligned}$$

We still have a integral of a product to compute. We apply the integral by part once more,

$$\begin{aligned}&= -e^\pi - 1 - (e^x (-\sin x) \Big|_0^\pi + \int_0^\pi e^x (\cos x) dx). \\ &= -e^\pi - 1 - \int_0^\pi e^x (\cos x) dx.\end{aligned}$$

With this new integration, we just came back to our initial integral. We are looping, and further integrations by part will not help us. To break the loop, we use the fact that the initial integral term is present on both side of the equation and solve for it. If

$$I = \int_0^\pi \cos x e^x dx,$$

then

$$\begin{aligned}I &= -e^\pi - 1 - I, \\2I &= -e^\pi - 1, \\I &= \frac{-e^\pi - 1}{2}.\end{aligned}$$

Et voilà!

Solution to exercise 4

1. linear, non-autonomous, not in normal form
2. non-linear, non-autonomous, not in normal form
3. non-linear, autonomous, not in normal form
4. non-linear, autonomous, not in normal form
5. non-linear, non-autonomous, not in normal form

Solution to exercise 5 The initial condition $x(0) = 1$ tells us to start the integration at $t = 0$. Using the second method with $a(t) = 2$ and $b(t) = 6$, we have

$$x(t) = K e^{-\int_0^t -\frac{6}{2} du} = K e^{-\frac{6}{2}t}.$$

The constant K is determined by the initial condition,

$$x(0) = K e^0 = K = 1.$$

The complete solution is

$$x(t) = e^{-\frac{6}{2}t}.$$

Solution to exercise 6 The initial condition $x(1) = 1$ tells us to start the integration at $t = 1$. Using the second method with $a(t) = 1$ and $b(t) = 1/t$, we have

$$x(t) = K e^{-\int_1^t -\frac{1}{u} du} = K e^{-\ln u|_1^t} = K e^{-\ln t}.$$

The term $e^{-\ln t} = e^{\ln t^{-1}} = t^{-1}$. The solution simplifies to

$$x(t) = \frac{K}{t}.$$

The constant K is found with the initial condition $x(1) = K = 1$, for a complete solution $x(t) = \frac{1}{t}$.

Solution to exercise 7 $\bar{z} = 2 - 3i$, $|z| = \sqrt{2^2 + 3^2} = \sqrt{13}$, $|\bar{z}| = \sqrt{2^2 + (-3)^2} = \sqrt{13}$, we see that $|z| = |\bar{z}|$, $\Re(\bar{z}) = 2$, $\Im(\bar{z}) = -3$, $\frac{z+\bar{z}}{2} = (2 + 3i + (2 - 3i))/2 = 2$, $\frac{z-\bar{z}}{2} = ((2 + 3i - (2 - 3i))/2 = 3i$, $-z = -2 - 3i$, $iz = 2i + 3i^2 = -3 + 2i$.

Solution to exercise 8 The modulus of z is $|z| = \sqrt{r^2 \cos^2(\theta) + r^2 \sin^2(\theta)} = \sqrt{r^2} = r$. From Euler's formula, we have $\cos(\theta) + i \sin(\theta) = e^{i\theta}$, so $z = re^{i\theta}$. Therefore, for any complex number $z = re^{i\theta}$, $|z| = 1$ if and only if $r = 1$.

Solution to exercise 9 All trigonometric identities can be obtained by applying Euler's formula. Here we start from $e^{ia+ib} = \cos(a+b) + i \sin(a+b)$. We only want the real part,

$$\begin{aligned} \cos(a+b) &= \frac{e^{ia+ib} + e^{-ia-ib}}{2} \\ &= \frac{e^{ia}e^{ib} + e^{-ia}e^{-ib}}{2} \\ &= \frac{(\cos(a) + i \sin(a))(\cos(b) + i \sin(b)) + (\cos(a) - i \sin(a))(\cos(b) - i \sin(b))}{2} \\ &= \frac{\cos(a)\cos(b) + i^2 \sin(a)\sin(b) + i \cos(a)\sin(b) + i \cos(b)\sin(a)}{2} \\ &\quad + \frac{\cos(a)\cos(b) + i^2 \sin(a)\sin(b) - i \cos(a)\sin(b) - i \cos(b)\sin(a)}{2} \end{aligned}$$

The mixed cosine-sine terms cancel each other while the other ones add up, resulting in

$$\cos(a+b) = \cos(a)\cos(b) - \sin(a)\sin(b).$$

Solution to exercise 10 This is a direct application of Euler's formula: $e^{i\pi} = \cos(\pi) + i \sin(\pi) = -1$.

Solution to exercise 11 The roots must satisfy $e^{i6\theta} = 1$. This means that $\theta = \frac{2}{6}k\pi$, for $k = 0, 1, \dots, 5$. There are six distinct roots.

Solution to exercise 12 The exponential converges to zero if and only if $\Re(z) < 0$. A complex number is close to zero if and only if its modulus is close to zero. Therefore, to show that a quantity converges to zero, it is necessary and sufficient to show that its modulus converges to zero. If $z = a + ib$, the exponential $e^{zt} = e^{(a+ib)t} = e^{at}e^{ibt}$. The modulus $|e^{ibt}| = 1$, so $|e^{zt}| = e^{at}$ (no need for absolute values, the exponential of a real number is always positive). The condition for convergence to zero is therefore a condition on the real part of z : $e^{at} \rightarrow 0$ when $t \rightarrow \infty$ if and only if $a < 0$.

Solution to exercise 13 The square root of a complex number always exists. Express z in polar form $z = re^{i\theta}$, $r \geq 0, \theta \in [0, 2\pi]$. The square root $\sqrt{z} = \sqrt{r}\sqrt{e^{i\theta}} = \sqrt{r}e^{\frac{1}{2}i\theta}$. Using Euler's formula, $\sqrt{z} = \sqrt{r}\cos(\theta/2) + i\sqrt{r}\sin(\theta/2)$. That is, the square root is obtained by taking the square root of the modulus r , and dividing the angle (the **argument**) by 2. There is a problem with this solution, because z can also be represented by $re^{i\theta+2\pi}$, giving $\sqrt{z} = \sqrt{r}e^{\frac{1}{2}i\theta+\pi}$, which is equivalent to dividing the angle by two in the other direction. We define the **principal square root** as the solution that makes the smallest change in angle: $\sqrt{z} = \sqrt{r}e^{\frac{1}{2}i\theta}$ if $\theta \in [0, \pi]$, and $\sqrt{z} = \sqrt{r}e^{\frac{1}{2}i\theta+\pi}$ if $\theta \in (\pi, 2\pi]$ To express the solution in terms of the original form of $z = a + ib$, we express the square root $s = \alpha + i\beta$. Then $s^2 = \alpha^2 - \beta^2 + 2i\alpha\beta = z = a + ib$. By identifying the real and imaginary parts, we get two equations: $\alpha^2 - \beta^2 = a$ and $2i\alpha\beta = b$. Denoting the modulus of z by $r = \sqrt{a^2 + b^2}$, we can obtain the solutions

$$\alpha = \frac{1}{\sqrt{2}}\sqrt{a+r}, \quad \beta = \text{sign}(b)\frac{1}{\sqrt{2}}\sqrt{-a+r}.$$

Solution to exercise 14

$$\begin{pmatrix} 0 & -1 \\ 1 & 0 \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \end{pmatrix} = \begin{pmatrix} -x_2 \\ x_1 \end{pmatrix}.$$

The transformation is a 90 degree counterclockwise rotation.

Solution to exercise 15

$$\begin{pmatrix} 0 & -1 \\ 1 & 0 \end{pmatrix} \begin{pmatrix} 1 & 0 \\ 0 & -1 \end{pmatrix} = \begin{pmatrix} 0 & 1 \\ 1 & 0 \end{pmatrix}.$$

This matrix exchanges the coordinates of a vector, this is a reflection through the axis $x = y$.

Solution to exercise 16

$$\begin{pmatrix} 1 & 0 \\ 0 & -1 \end{pmatrix} \begin{pmatrix} 0 & -1 \\ 1 & 0 \end{pmatrix} = \begin{pmatrix} 0 & -1 \\ -1 & 0 \end{pmatrix}.$$

The product is not the same, the matrices do not commute. The transformation is now a reflection through $y = -x$.

Solution to exercise 17 The matrix is

$$\begin{pmatrix} a & 0 \\ 0 & b \end{pmatrix}.$$

Solution to exercise 18 The matrix is

$$\begin{pmatrix} 0 & 1 \\ 1 & 0 \end{pmatrix}.$$

Solution to exercise 19 The matrix is

$$\begin{pmatrix} 0 & 1 \\ 0 & 0 \end{pmatrix}.$$

Solution to exercise 20 The power of a diagonal matrix is a diagonal matrix

$$A^k = \begin{pmatrix} a^k & 0 \\ 0 & b^k \end{pmatrix}.$$

Solution to exercise 21 The scalar product is

$$\begin{aligned} x^*y &= (1 - 2i, 1 + i)(0.5 - i, -0.5)^t \\ &= (1 - 2i)(0.5 - i) + (1 + i)(-0.5) \\ &= 0.5 + 2i^2 - 2(0.5)i - i - 0.5 - 0.5i \\ &= (0.5 - 0.5 + 2i^2) + (-2(0.5) - 1 - 0.5)i \\ &= -2 - 2.5i. \end{aligned}$$

Solution to exercise 22 The scalar product is

$$\begin{aligned} y^*x &= (0.5 + i, -0.5)(1 + 2i, 1 - i)^t \\ &= (0.5 + i)(1 + 2i) + (-0.5)(1 - i) \\ &= 0.5 + 2i^2 + i + 2(0.5)i - 0.5 + 0.5i \\ &= -2 + 2.5i \end{aligned}$$

This is the conjugate: $x^*y = (y^*x)^*$.

Solution to exercise 23 The scalar product $z^*z = (\bar{z}_1, \bar{z}_2)(z_1, z_2)^t = \bar{z}_1z_1 + \bar{z}_2z_2 = |z_1|^2 + |z_2|^2$. The scalar product is the square of the norm of the vector z .

Solution to exercise 24 We have $\det A = (-1)(-1) - (2)(2) = 1 - 4 = -3 < 0$, $\operatorname{tr} A = -1 - 1 = -2$, and $\Delta = (-2)^2 - 4(-3) = 4 + 12 = 16$. The eigenvalues

are

$$\lambda_{1,2} = \frac{1}{2}(-2 \pm \sqrt{16}) = -1 \pm 2 = 1, -3.$$

The two eigenvalues are distinct, so the matrix A is diagonalisable. The eigenvector associated with the eigenvalue $\lambda_1 = 1$ is solution to the eigenproblem $(A - \lambda_1 I)x = 0$. We look for a solution

$$\begin{pmatrix} -1 - (1) & 2 \\ 2 & -1 - (1) \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \end{pmatrix} = 0,$$

$$\begin{pmatrix} -2 & 2 \\ 2 & -2 \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \end{pmatrix} = 0.$$

(We check that the two rows are colinear.) The first row gives $-2x_1 + 2x_2 = 0$, or $x_1 = x_2$. The norm of the eigenvector $x = (x_1, x_2)^t = \sqrt{x_1^2 + x_2^2} = \sqrt{2}|x_1|$. We choose $x_1 = 1/\sqrt{2}$ to have a normalized eigenvector. We know that the second eigenvector is orthogonal to x , so we can take $y = (1/\sqrt{2}, -1/\sqrt{2})^t$ for the eigenvector associated to $\lambda_2 = -3$. To check that this is indeed an eigenvector, we solve to eigenproblem

$$\begin{pmatrix} -1 - (-3) & 2 \\ 2 & -1 - (-3) \end{pmatrix} \begin{pmatrix} y_1 \\ y_2 \end{pmatrix} = 0,$$

$$\begin{pmatrix} 2 & 2 \\ 2 & 2 \end{pmatrix} \begin{pmatrix} y_1 \\ y_2 \end{pmatrix} = 0.$$

The solutions are vectors that satisfy $y_1 = -y_2$; this is the case for y . The matrix X is composed of the column vectors x and y : $X = (x|y)$ and its inverse is

$$X^{-1} = X^t = \begin{pmatrix} x_1^t \\ x_2^t \end{pmatrix} = \frac{1}{\sqrt{2}} \begin{pmatrix} 1 & 1 \\ 1 & -1 \end{pmatrix}.$$

Solution to exercise 25 The steady states are found by solving

$$f_1(x, y) = -dx + x \exp(-axy) = 0,$$

$$f_2(x, y) = x - y = 0.$$

From the second equation, we have $x = y$. The first equation is equivalent to $dx = x \exp(-axy)$. We need to distinguish two cases: (i) $x = 0$, and (ii) $x \neq 0$. Case (i) leads to the solution $x^* = (0, 0)^t$, our first steady state. Case (ii) means that we can simplify x in the first equation: $d = \exp(-axy)$. Replacing $y = x$, and solving for

x :

$$\begin{aligned} d &= \exp(-axy), \\ d &= \exp(-ax^2), \\ \ln d &= -ax^2, \\ -\frac{\ln d}{a} &= x^2, \quad (a > 0) \end{aligned}$$

The hypothesis $d < 1$ ensures that $\ln d < 0$ and $-\ln d > 0$. There are therefore two real solutions for x :

$$x = \pm \sqrt{-\frac{\ln d}{a}}.$$

The two additional steady states are

$$\bar{\mathbf{x}}_{1,2} = \begin{pmatrix} \pm \sqrt{-\frac{\ln d}{a}} \\ \pm \sqrt{-\frac{\ln d}{a}} \end{pmatrix}.$$

The Jacobian matrix of \mathbf{f} is computed from the partial derivatives

$$\begin{aligned} \frac{\partial f_1}{\partial x}(x, y) &= -d + (-ay) \exp(-axy), \\ \frac{\partial f_1}{\partial y}(x, y) &= (-ax) \exp(-axy), \\ \frac{\partial f_2}{\partial x}(x, y) &= 1, \\ \frac{\partial f_2}{\partial y}(x, y) &= -1. \end{aligned}$$

$$\mathbf{J} = \begin{pmatrix} -d - ay \exp(-axy) & -ax \exp(-axy) \\ 1 & -1 \end{pmatrix}.$$

The function f_2 is linear. This is reflected in the Jacobian matrix, which has constant coefficients on the second row. The evaluation of the Jacobian matrix at steady state $\mathbf{x}^* = (0, 0)^t$ is

$$\mathbf{J}(\mathbf{x}^*) = \begin{pmatrix} -d & 0 \\ 1 & -1 \end{pmatrix}.$$

The evaluation of Jacobian matrix at steady state $\bar{\mathbf{x}}_1 = \left(\sqrt{-\frac{\ln d}{a}}, \sqrt{-\frac{\ln d}{a}}\right)^t$ is

$$\mathbf{J}(\bar{\mathbf{x}}_1) = \begin{pmatrix} -d - a\bar{y}_1 \exp(-a\bar{x}_1\bar{y}_1) & -a\bar{x}_1 \exp(-a\bar{x}_1\bar{y}_1) \\ 1 & -1 \end{pmatrix}.$$

Here, we use the fact that steady states satisfy the equation $\exp(-axy) = d$ to simplify

the exponential terms

$$\mathbf{J}(\bar{\mathbf{x}}_1) = \begin{pmatrix} -d - a\bar{y}_1 d & -a\bar{x}_1 d \\ 1 & -1 \end{pmatrix}.$$

Replacing y_1 and x_1 by $\sqrt{-\frac{\ln d}{a}}$, we obtain

$$\begin{aligned} \mathbf{J}(\bar{\mathbf{x}}_1) &= \begin{pmatrix} -d - a y_1 d & -a \bar{x}_1 d \\ 1 & -1 \end{pmatrix}, \\ &= \begin{pmatrix} -d - a \sqrt{-\frac{\ln d}{a}} d & -a \sqrt{-\frac{\ln d}{a}} d \\ 1 & -1 \end{pmatrix}, \\ &= \begin{pmatrix} -d \left(1 + a \sqrt{-\frac{\ln d}{a}}\right) & -d \sqrt{-a^2 \frac{\ln d}{a}} \\ 1 & -1 \end{pmatrix}, \\ &= \begin{pmatrix} -d \left(1 + \sqrt{-a \ln d}\right) & -d \sqrt{-a \ln d} \\ 1 & -1 \end{pmatrix}. \end{aligned}$$

The same lines of calculations for the steady state $\bar{\mathbf{x}}_2$ leads to

$$\mathbf{J}(\bar{\mathbf{x}}_2) = \begin{pmatrix} -d \left(1 - \sqrt{-a \ln d}\right) & d \sqrt{-a \ln d} \\ 1 & -1 \end{pmatrix}.$$

13 Glossary

French	English	Note
dérivable	differentiable	
matrice jacobienne	Jacobian matrix	
rang	rank	
noyau	kernel	notation: \ker
ensemble	set	
espace vectoriel	vector space	
sous-espace vectoriel	linear subspace	
valeur propre	eigenvalue	
vecteur propre	eigenvector	
sous-espace propre	eigenspace	
décomposition en valeurs propres	eigenvalue decomposition	
décomposition en valeurs singulières	singular value decomposition	
valeur singulière	singular value	
trace	trace	
déterminant	determinant	\det
base	basis	
application linéaire	linear map	
application	map	
dimension	dimension	
moindres carrés	least-squares	
produit scalaire	scalar product	
Vect	Span	
famille libre	linearly independent set	
famille génératrice	spanning set	