Dfferent Quotient → Derivative → Partial Derivative → Chainrule
Gradient , → Jacobian /

Chapters Vector Calculus

Difference Quotient # 3

$$\frac{\delta y}{\delta x} := \frac{f(a+\delta x) - f(x)}{\delta x}$$

Derivative differentiation OF

$$\frac{df}{da} := \lim_{h \to 0} \frac{f(a+h) - f(h)}{h}$$

Partial Denvotive 型肥

$$\frac{\partial f}{\partial A_{1}} = \lim_{h \to 0} \frac{f(A_{1}+h_{1}, A_{2}, A_{n}) - f(A_{1})}{h}$$

$$\nabla_{A} f = \operatorname{grad} f = \frac{df}{dA_{1}}$$

$$= \left[\begin{array}{cc} \frac{of(a)}{va_1} & \frac{of(a)}{va_2} & \frac{of(a)}{va_n} \right] \in \mathbb{R}^{1\times n}$$

column veder isen

Chan Rule.

$$\frac{df}{dt} = \left[\frac{Df}{Da_1} \frac{Df}{Da_2} \right] \left[\frac{\frac{DA_1(t)}{Dt}}{\frac{Aa_1(t)}{Dt}} \right]$$

$$= \frac{\partial f}{\partial \alpha_1} \frac{\partial d_1}{\partial t} + \frac{\partial f}{\partial a_2} \frac{\partial \alpha_2}{\partial t}$$

Jacobian Motors Jacobian 23

$$J = \nabla_{\alpha} f = \frac{\partial f(\alpha)}{\partial \alpha}$$

$$= \begin{bmatrix} \frac{\partial f_{1}(\alpha)}{\partial \alpha_{1}} & \frac{\partial f_{2}(\alpha)}{\partial \alpha_{1}} \\ \vdots & \vdots & \vdots \\ \frac{\partial f_{m}(\alpha)}{\partial \alpha_{1}} & \frac{\partial f_{m}(\alpha)}{\partial \alpha_{1}} \end{bmatrix}$$

(→ Jacobian / Hessian Motnx → Multivanate Taylor Senes

Gradient 1801 of a Vector-Valved Function.

$$\frac{\partial f}{\partial x} = \begin{bmatrix} \frac{\partial f_1}{\partial x} & \frac{\partial f_2}{\partial x} \\ \frac{\partial f_m}{\partial x} & \frac{\partial f_m}{\partial x} \end{bmatrix} = \begin{bmatrix} A_{11} & A_{1N} \\ A_{1N} & A_{1N} \\ A_{2N} & A_{2N} \end{bmatrix}$$

$$= A \in \mathbb{R}^{M \times N}.$$

Higer-Order Denivotves

- Taylor Polynomial.

$$T_n(z) := \sum_{k=0}^n \frac{f^{(k)}(x_0)}{k!} (x_0)^k$$

-Taylor Series

$$T_{\infty}(A) = \sum_{k=0}^{\infty} \frac{f^{(k)}(A_0)}{k!} (A - A_0)^k$$

- Multivanate Taylor Sones.

- Taylor Polynomial.

$$T_n(x) = \sum_{k=0}^n \frac{D_x^k f(x_0)}{k!} (x_0 - f_0)^k$$

Hessian Motor Hessian sys

$$H_{\mu} = \begin{bmatrix} \frac{\partial f}{\partial \lambda_{1}^{2}} & \frac{\partial^{2} f}{\partial \lambda_{1} \partial \lambda_{2}} & \frac{\partial^{2} f}{\partial \lambda_{1} \partial \lambda_{2}} \\ \frac{\partial^{2} f}{\partial \lambda_{1} \partial \lambda_{1}} & \frac{\partial^{2} f}{\partial \lambda_{1} \partial \lambda_{2}} & \frac{\partial^{2} f}{\partial \lambda_{1} \partial \lambda_{2}} \end{bmatrix}$$

$$(\mathcal{H}_{\mathcal{L}})_{i,j} = \frac{\nabla f}{\nabla a_i \nabla a_j}$$
$$= \frac{\nabla}{\partial a_i} \left(\frac{\nabla f}{\nabla a_j}\right)$$