

MTH 421



NATIONAL OPEN UNIVERSITY OF NIGERIA

SCHOOL OF SCIENCE AND TECHNOLOGY

COURSE CODE: MTH421

COURSE TITLE: ORDINARY DIFFERENTIAL EQUATIONS

MTH 421

ORDINARY DIFFERENTIAL EQUATIONS

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Course Materials

These include:

1. Course Guide
2. Study Units
3. Recommended Texts
4. Tutor Marked Assignments.
5. Presentation Schedule

Study Units

There are thirteen study units in this course:

MODULE ONE:

- UNIT 1: Ordinary Differential Equations
UNIT 2: Existence and Uniqueness Theorems
UNIT 3: Properties of Solutions

MODULE TWO:

- UNIT 4: Linear Systems
UNIT 5: Adjoint Systems

MODULE THREE

- UNIT 6: Sturm-Liouville Boundary Value Problems
UNIT 7: Linear Operator on Hilbert Spaces
UNIT 8: Stability Theory

MODULE 1

UNIT 1: ORDINARY DIFFERENTIAL EQUATIONS

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1 Introduction

2 Objectives

(1)

(2)

(3)

order

2 Objectives

3 Main Content

3.1 First Order ODEs

3.1.1 Concept of Solution

solution

3.1 First Order ODEs

Example 3.1

/

-

Solution.

-

-

-

-

Example 3.2

—

general solution
particular solution

3.1.2 Initial Value Problem (IVP)

initial condition

initial value problem (IVP)

Example 3.3

—

Solution.

3.1 First Order ODEs

3.1.3 Separable ODEs.

—

separable equation

method of separating variables

Example 3.4

Solution.

—

—

Example 3.5

Solution.

—

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3.1 First Order ODEs

Reduction to Separable Form

Example 3.6

Solution.

3.1 First Order ODEs

3.1.4 Exact ODEs.

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— - ———

exact differential equation

exact

— —

implicit solution,

(a) —

(b) —

— — — —

3.1 First Order ODEs

— —

Example 3.7

Solution.

Step 1. Test for exactness.

— —

Step 2. Implicit general solution.

— —

3.1 First Order ODEs

3.1 First Order ODEs

Step 3. Checking an implicit solution.

— —

Example 3.8 WARNING! Breakdown in the Case of Nonexactness

- - -

- - -

Reduction to Exact Form. Integrating Factors

-
-
_____ - - - -

factor of (20).

integrating

Example 3.9 Integrating Factor

-
_____ - - - -

-

- _____ - _____ - _____ - _____

3.1 First Order ODEs

— —

3.1 First Order ODEs

Solution.

Step 1. Nonexactness.

Step 2. Integrating factor. General solution.

Step 3. Particular solution.

Step 4. Checking.

3.1.5 Linear ODEs. Bernoulli Equation.

linear

any

3.1 First Order ODEs

“ standard form” (1)

Homogeneous Linear ODE.

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homogeneous.

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≈

trivial solution

Nonhomogeneous Linear ODE.

/

nonhomogeneous.

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3.1 First Order ODEs

Example 3.11 First-Order ODE, General Solution

Solution.

Example 3.12 First-Order ODE, Initial Value Problem.

/ /

Reduction to Linear Form. Bernoulli Equation

Bernoulli equation.

Example 3.13 Logistic Equation.

logistic equation Verhulst equation

Solution.

3.2 Second Order Linear ODEs

3.2 Second Order Linear ODEs

Homogeneous Linear ODEs: Superposition Principle

Example 3.14 Homogeneous Linear ODEs: Superposition of Solutions

linear combination

superposition principle linearity principle.

Theorem 3.3 Fundamental Theorem for the Homogeneous Linear ODE (38)

Proof.

...



Remark 3.1

does not hold

3.2 Second Order Linear ODEs

Example 3.15 A Nonhomogeneous Linear ODE

Example 3.16 A Nonlinear ODE

Initial Value Problem. Basis. General Solution

initial conditions

initial value problem

general solution

particular solution

Example 3.17 Initial Value Problem

Solution.

Step 1. General solution.

Step 2. Particular solution.

3.2 Second Order Linear ODEs

Definition 3.1 General Solution, Basis, Particular Solution
general solution

fundamental system
particular solution

basis

(a)

(b)

linearly independent

linearly dependent

Definition 3.2 Basis (Reformulated)
basis

Example 3.18

3.2 Second Order Linear ODEs

3.2.1 Homogeneous Linear ODEs with Constant Coefficients

characteristic equation

$$r^2 + ar + b = 0$$

- (Case I) -
 - (Case II) -
 - (Case III) -
-

3.2 Second Order Linear ODEs

Case I. Two Distinct Real Roots and

Example 3.20

Example 3.21

Solution.

Step 1. General solution.

Step 2. Particular solution.

3.2 Second Order Linear ODEs

Case II. Real Double Root

Example 3.22

Example 3.23

Solution.

3.2 Second Order Linear ODEs

Case III. Complex Roots - - and - - -

Example 3.24

Solution.

Step 1. General solution.

- ±

Step 2. Particular solution.

Example 3.25 Complex Roots

3.2 Second Order Linear ODEs

3.2.2 Nonhomogeneous ODEs

Method of Undetermined Coefficients

/

Definition 3.3 General Solution, Particular Solution
general solution

Particular solution

Theorem 3.4 Relations of Solutions of (53) to Those of (54)

(a)

(b)

Proof.

(a)

(b)

- - -

■

3.2 Second Order Linear ODEs

Theorem 3.5 A General Solution of a Nonhomogeneous ODE includes All Solutions

Proof.

■

Method of Undetermined Coefficients

method of undetermined coefficients.

coefficients a and b *constant*

Method of Undetermined Coefficients

...	- ...
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3.2 Second Order Linear ODEs

Example 3.26 Application of the Basic Rule (a)

Solution.

Step 1. General solution of the homogeneous ODE.

Step 2. Solution of the nonhomogeneous ODE.

Step 3. Solution of the initial value problem.

Example 3.27 Application of the Modification Rule (b)

Solution.

Step 1. General solution of the homogeneous ODE.

Step. 2 Solution of the nonhomogeneous ODE.

3.2 Second Order Linear ODEs

Step 3. Solution of the initial value problem.

Example 3.28 Application of the Sum Rule (c)

Solution.

Step 1. General solution of the homogeneous ODE.

Step 2. Solution of the nonhomogeneous ODE.

3.2 Second Order Linear ODEs

Step 3. Solution of the initial value problem.

3.2.3 Solution by Variation of Parameters

method of variation of parameters

4 Conclusion

Example 3.29 Method of Variation of Parameters

Solution.

3.3 Higher Order Linear ODEs

th order

linear

coefficients

3.3 Higher Order Linear ODEs

standard form.

nonlinear.

homogeneous.
solution

nonhomogeneous.

4 Conclusion

higher order . first order, second order of

5 Summary

first order

general solution,

initial condition
initial value problem

particular solution

6 Tutor Marked Assignments(TMAs)

exact ODE

differential

integrating factor

Linear ODEs

Bernoulli equation

second-order

linear

homogeneous

/

nonhomogeneous

by superposition principle

**fundamental system
general solution**

a basis

particular solution

6 Tutor Marked Assignments(TMAs)

6 Tutor Marked Assignments(TMAs)

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UNIT 2: EXISTENCE AND UNIQUENESS THEOREM

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Tutor Marked Assignments (TMAs)

1 Introduction

2 Objectives

3 Main Content

3.1 Existence and Uniqueness Theorem of First-Order Equations

3.1.1 Some Concepts from Real Function Theory

Uniform Convergence

Definition 3.1 (Convergent Sequence of Real Numbers) $\{ \}$

$$| - |$$

Definition 3.2 (Pointwise Convergence) $\{ \}$

$$| - |$$

Definition 3.3 (Uniform Convergence) $\{ \}$

$$| - |$$

Example 3.1 $\{ \}$

Solution.

3.1 Existence and Uniqueness Theorem of First-Order Equations

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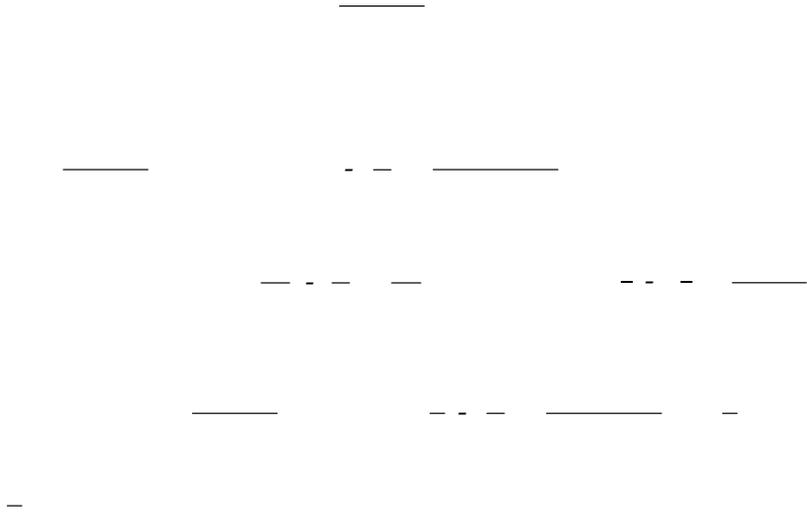
Theorem 3.1 { }

Example 3.2 { }

Theorem 3.2 { }

Example 3.3 { }

3.1 Existence and Uniqueness Theorem of First-Order Equations



series

Definition 3.4

{ }

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{ }

Theorem 3.3 (Weierstrass M-Test) { }

| |

3.1 Existence and Uniqueness Theorem of First-Order Equations

Example 3.4

Functions of Two Real Variables; the Lipschitz Condition.

Definition 3.5

connected

open

domain.

boundary point

closed domain.

Example 3.5

Definition 3.6

Definition 3.7

bounded

/ /

3.1 Existence and Uniqueness Theorem of First-Order Equations

Theorem 3.4

Example 3.6

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Definition 3.8

Lipschitz Condition

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Lipschitz Constant.

Theorem 3.5

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Example 3.7

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Example 3.8

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3.1 Existence and Uniqueness Theorem of First-Order Equations

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3.1 Existence and Uniqueness Theorem of First-Order Equations

3.1.2 Existence and Uniqueness of Solutions

The Basic Problem and a Basic Lemma

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Lemma 3.1

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Proof.

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The Existence and Uniqueness Theorem.

Theorem 3.6

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$$| - | \quad | - |$$

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Remark 3.1

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$$| - |$$

$$| - |$$

$$| - |$$

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3.1 Existence and Uniqueness Theorem of First-Order Equations

Method of Proof

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successive approximations (Picards Iterants)

$$\left| \begin{matrix} \{ \} \\ - \\ \{ \} \end{matrix} \right| \quad | - |$$

$$| - - | \quad \text{---} \quad | - |$$

$$| - | \quad \{ \}$$

$$\text{---} \quad | - |$$

$$| - |$$

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Remarks and Examples

3.1 Existence and Uniqueness Theorem of First-Order Equations

$$y' = -y$$

Example 3.9

$$y' = -y$$

$$y' = -y \quad y(0) = 1$$

$$y' = -y \quad y(0) = 1$$

-

$$y' = -y \quad y(0) = 1$$

$$y' = -y$$

-

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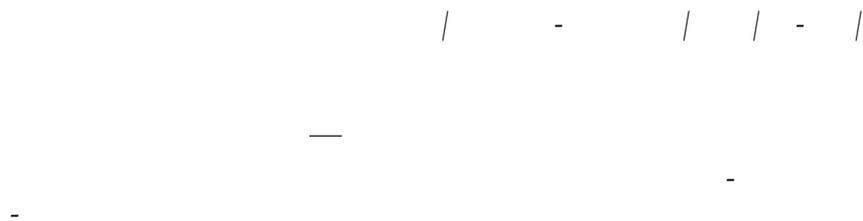
$$y' = -y$$

3.1 Existence and Uniqueness Theorem of First-Order Equations

Example 3.10



Theorem 3.7



3.1 Existence and Uniqueness Theorem of First-Order Equations

3.1 Existence and Uniqueness Theorem of First-Order Equations

3.1.3 Dependence of Solutions on Initial Condition and on the Function



Theorem 3.8



3.1 Existence and Uniqueness Theorem of First-Order Equations

$$| - |$$

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Theorem 3.9

$$| - |$$

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$$| - |$$

$$| - | \quad | - | \quad | - |$$

$$| - |$$

Example 3.11

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$$| - | \quad | \quad |$$

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3.2 Existence and Uniqueness Theorem of Linear Differential Equations

3.2.1 The Basic Existence Theorem

Consider the linear differential equation

$$y' + P(x)y = Q(x)$$

where $P(x)$ and $Q(x)$ are continuous functions on an interval I containing the point x_0 . The initial condition is $y(x_0) = y_0$.

The theorem states that there exists a unique solution $y(x)$ defined on the interval I that satisfies the differential equation and the initial condition.

Definition 3.9

3.2 Existence and Uniqueness Theorem of Linear Differential Equations

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Definition 3.10

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solution

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Theorem 3.11

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3.2.2 Basic Existence and Uniqueness theorems on Linear Systems

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3.2 Existence and Uniqueness Theorem of Linear Differential Equations

$$/ \quad \dots \quad /$$

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$$/ \quad - \quad - \quad / \quad \frac{- \quad / \quad - \quad /}{-}$$

$$/ \quad - \quad - \quad / \quad \frac{-}{-}$$

$$/ \quad - \quad / \quad / \quad - \quad /$$

Theorem 3.13

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Proof.

$$\frac{-}{-}$$

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$$- \quad - \quad - \quad \dots \quad - \quad -$$

3.2 Existence and Uniqueness Theorem of Linear Differential Equations

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Example 3.12

$$\frac{1}{1-x} = 1 + x + x^2 + x^3 + \dots$$

Corollary 3.1

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Proof.



4 Conclusion

5 Summary

6 Tutor Marked Assignments(TMAs)

Exercise 6.1

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6 Tutor Marked Assigments(TMAs)

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UNIT 3: PROPERTIES OF SOLUTIONS OF LINEAR DIFFERENTIAL EQUATIONS

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Tutor Marked Assignments(TMAs)

1 Introduction

2 Objectives

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3.1 Basic Theory of Linear Differential Equations

3.1.1 Definition and Basic Existence Theorem

Definition 3.1 *Linear differential equation of order n*

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Example 3.1

Example 3.2 —

Theorem 3.1

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Example 3.3

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Example 3.4

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— — — —
— — — — —

Corollary 3.1

homogeneous

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— — — —

Example 3.5

3.1.2 The Homogeneous Equations

3.1 Basic Theory of Linear Differential Equations

Theorem 3.2 Basic Theorem on Linear Homogeneous Differential Equations

Definition 3.2

linear combination

Theorem 3.3 (Theorem 3.2 restated)

Example 3.6

Example 3.7

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Definition 3.3

linearly dependent

3.1 Basic Theory of Linear Differential Equations

Example 3.8

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Example 3.9

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Definition 3.4

linearly independent
linearly independent

Example 3.10

Theorem 3.4

Definition 3.5 (General Solution)

general solution

3.1 Basic Theory of Linear Differential Equations

Example 3.11

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Example 3.12

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Definition 3.6

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Wronskian

Theorem 3.5

Theorem 3.6

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Example 3.13

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Example 3.14

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3.1.3 Nonhomogeneous Equation

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(1)

Theorem 3.7

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(2)

Example 3.15

Definition 3.7

$$- \quad - \quad (1)$$

$$- \quad - \quad (2)$$

Example 3.16

3.2 General Theory for Linear Differential Equations with Constant Coefficient

3.2.1 Homogeneous Linear Equations with Constant Coefficients.

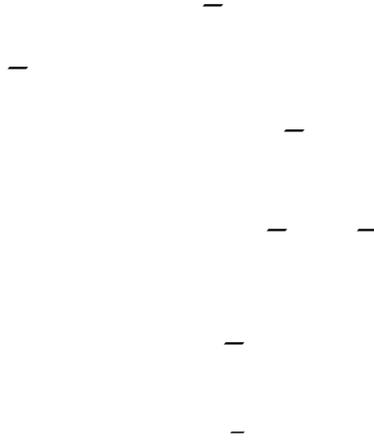
auxilliary equation *characteristic equation*

3.2.2 Case I. Distinct Real Roots

Theorem 3.8

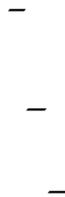
Example 3.17 –

Example 3.18 –



3.2.3 Case II. Repeated Real Roots

Example 3.19 An introductory Example.



Theorem 3.9

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Example 3.20

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Example 3.21

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3.2.4 Case III. Conjugate Complex Roots

Theorem 3.10

Example 3.22

Example 3.23

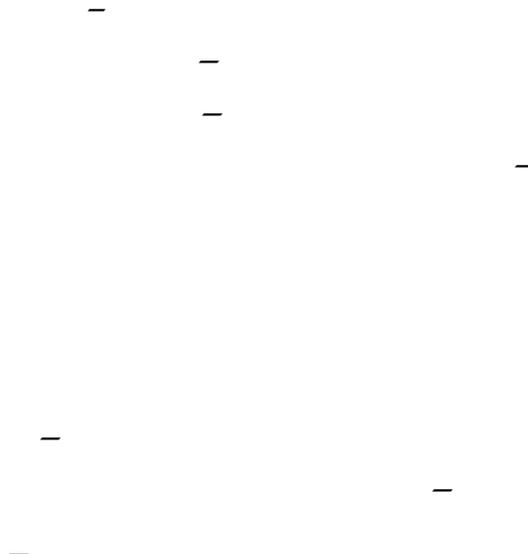


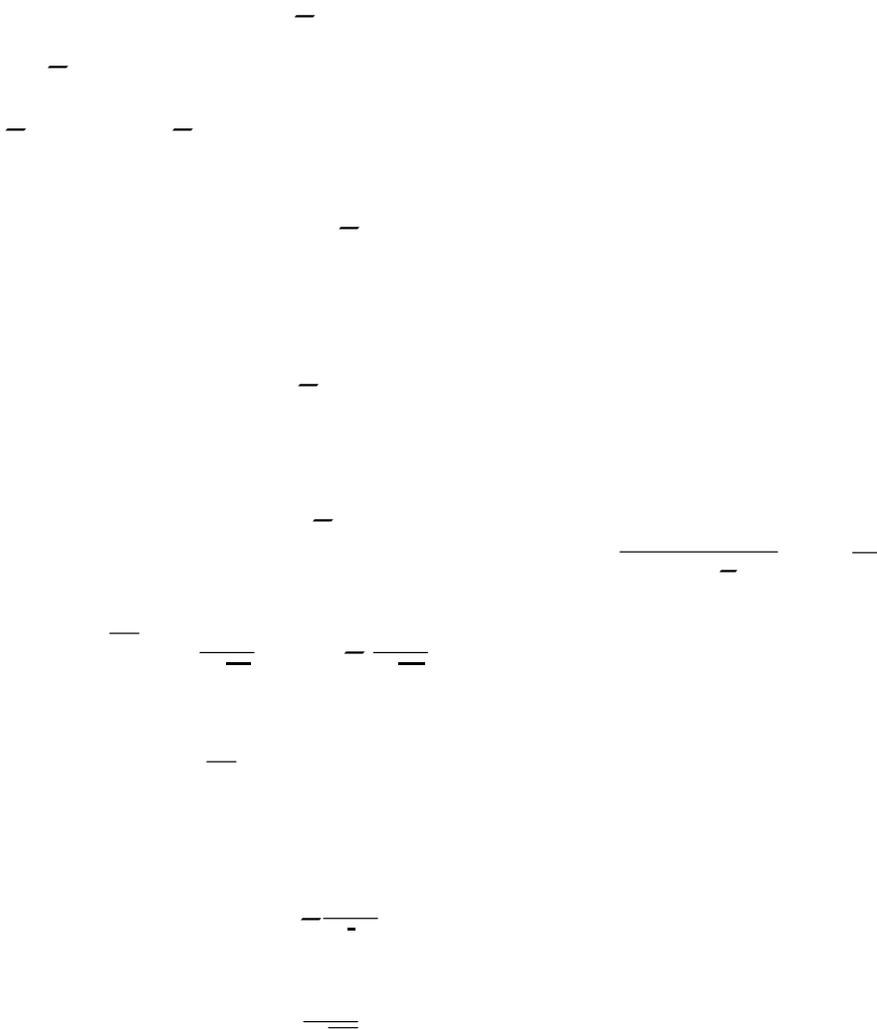
Example 3.24



3.2.5 An Initial-Value Problem

Example 3.25





3.2.6 The Method of Undetermined Coefficients



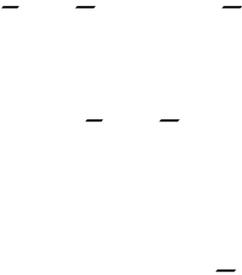
Definition 3.8

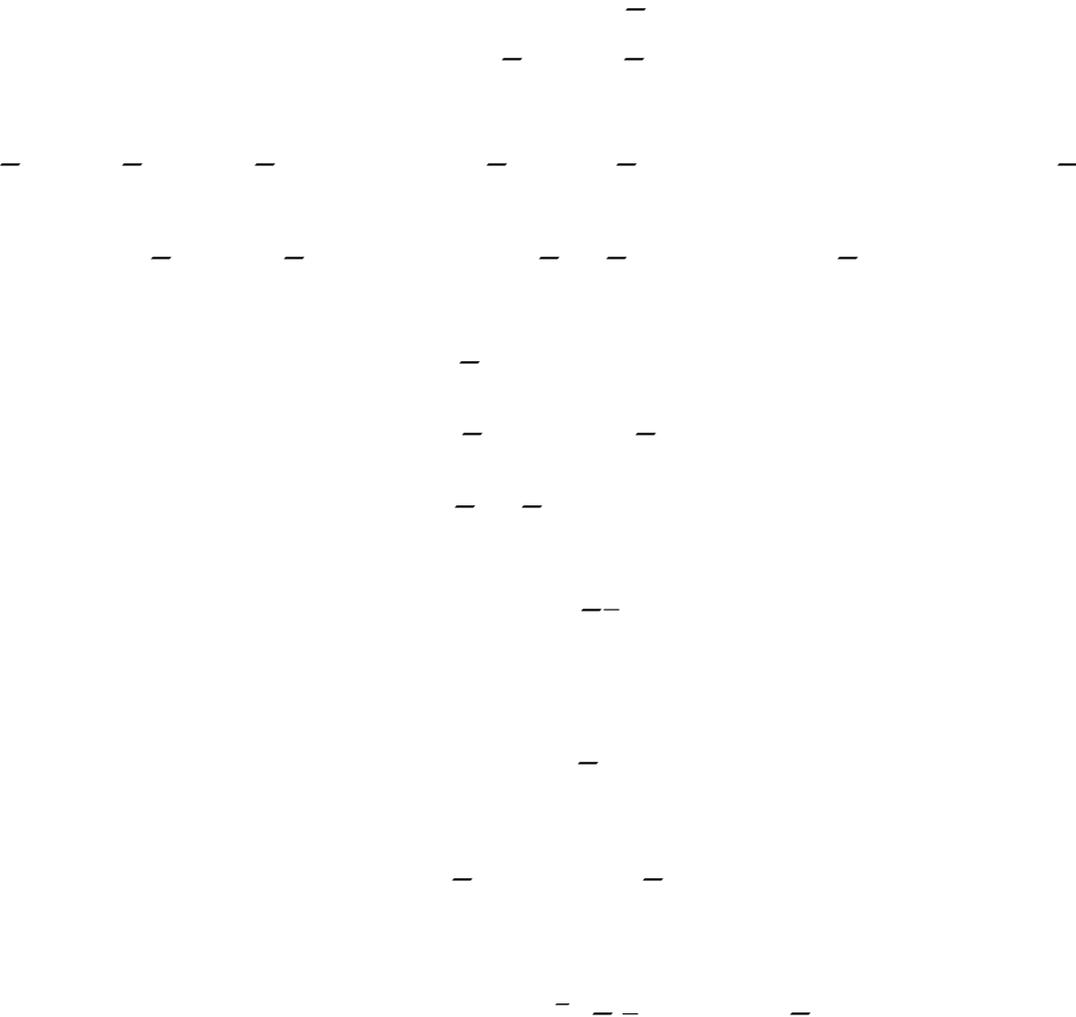
Definition 3.9

Example 3.26

Examples

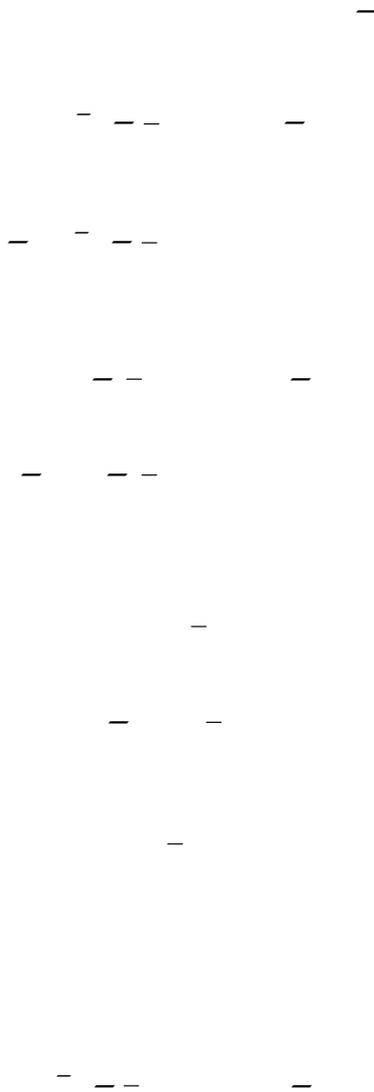
Example 3.27





Example 3.28 Initial-Value Problem





3.2.7 Variation Of Paramenters

The Method

$$\frac{y''}{y} = \frac{y''}{y}$$

$$\frac{y''}{y} = \frac{y''}{y}$$

$$\frac{y''}{y} = \frac{y''}{y}$$

Examples

Example 3.29

$$\frac{y''}{y} = \frac{y''}{y}$$

6 Tutor Marked Assignments(TMAs)

Exercise 6.1

(a)

(b)

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Exercise 6.2

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MODULE 2

UNIT 4: LINEAR SYSTEM

Contents

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Linear System

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Tutor Marked Assignments (TMAs)

1 Introduction

$$\frac{d^n x}{dt^n} + a_1(t) \frac{d^{n-1} x}{dt^{n-1}} + a_2(t) \frac{d^{n-2} x}{dt^{n-2}} + \dots + \frac{dx}{dt} + a_n(t)x = f(t)$$

$$\dot{x} = Ax + F(t) = f(t, x)$$

x

x

Linear systems

2 Objectives

homogeneous

nonhomogeneous

3 Linear System

3.1 Properties of Solution of Homogeneous Linear System

Definition 3.1

linear nonhomogeneous system. order

linear homogeneous system

Definition 3.2

Φ

solution

x

Φ

Φ

Φ

Definition 3.3

Φ

Φ

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3.1 Properties of Solution of Homogeneous Linear System

Lemma 3.1

$$\cdot \{ \quad \}$$

Proof of Lemma

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3.1 Properties of Solution of Homogeneous Linear System

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Proof of Theorem 1.3

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Remark 3.1

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3.3 Linear nonhomogeneous System

Theorem 3.4 Φ
 \times

Φ
 Φ

Proof.

Φ

$\dot{\Phi}$ Φ

$-\Phi$ $\dot{\Phi}$ Φ

Φ

Φ

Φ Φ /

Φ Φ

Φ Φ

Φ Φ^{-1} Φ $\Phi \Psi$ Φ

$\dot{\Phi}$ $\dot{\Phi} \Psi$ $\Phi \dot{\Psi}$

Φ $\dot{\Phi} \Psi$ $\Phi \dot{\Psi}$ $\Phi \dot{\Psi}$

$\dot{\Psi}$ Φ

■

3.2 The Adoint of the System (3)

Φ

Φ^{-1}

$\Phi \Phi^{-1}$

\times

$\dot{\Phi} \Phi^{-1}$ $\Phi \dot{\Phi}^{-1}$

$\Phi \Phi^{-1}$ $\Phi \dot{\Phi}^{-1}$

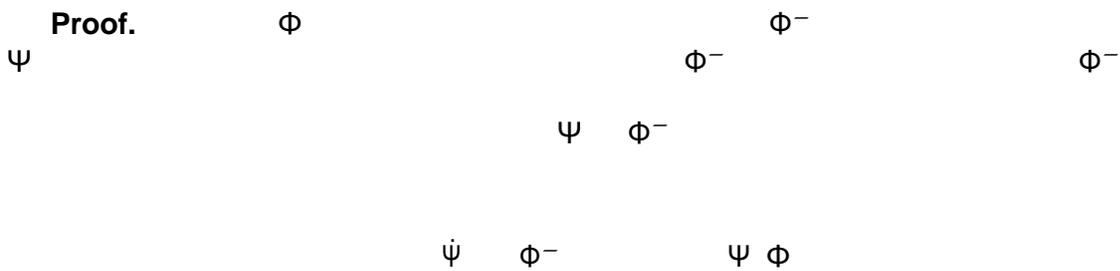
3.2 The Adjoint of the System (3)



Theorem 3.5 ϕ



Proof.



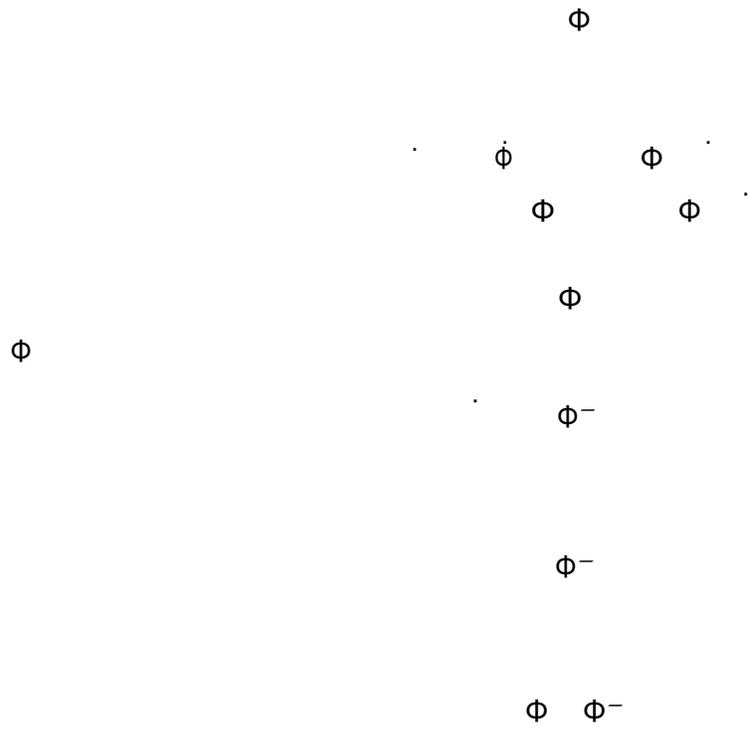
3.3 Linear nonhomogeneous System

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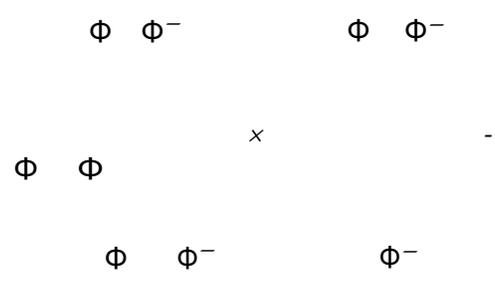
3.3.1 Variation of Parameter Technique



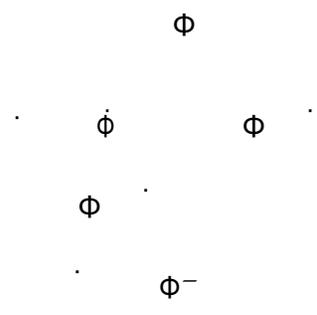
3.3 Linear nonhomogeneous System



Theorem 3.6



Proof. Φ



3.3 Linear nonhomogeneous System

$$\begin{array}{cccc}
 & & & \phi^- \\
 & & & \phi & \phi^- \\
 & & \phi & \phi^- & \phi^- \\
 & \phi & \phi^- & \phi & \phi^- \\
 & \phi & \phi^- & \phi^- & \phi^-
 \end{array}$$

■

Theorem 3.7

$$\begin{array}{cccc}
 & & & \phi & \phi \\
 & & & \phi & \phi \\
 & \phi & - & \phi & \phi \\
 & \phi & - & \phi & \phi
 \end{array}$$

Proof.

$$\begin{array}{cccc}
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 & \phi & - & \phi & \phi \\
 & \phi & - & \phi & \phi \\
 & \phi & - & \phi & \phi
 \end{array}$$

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3.4 Linear Homogenous Equation with constant Coefficients

3.4 Linear Homogenous Equation with constant Coefficients

x

c

c

c

-

c

c

solution

Theorem 3.8

Proof.

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3.4 Linear Homogenous Equation with constant Coefficients

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3.4 Linear Homogenous Equation with constant Coefficients

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3.4 Linear Homogenous Equation with constant Coefficients

Example 3.2

Solution.

3.4 Linear Homogenous Equation with constant Coefficients

3.4 Linear Homogenous Equation with constant Coefficients

$$\begin{aligned} & - - & - & - \\ & - - & - & - \\ & - - & - - & - \\ & - - & - & - \end{aligned}$$

Example 3.3

Solution.

$$- \quad \pm$$

Example 3.4

Solution.

3.4 Linear Homogenous Equation with constant Coefficients

$$| - |$$

$$- \pm$$

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$$\Phi \quad \Phi$$

$$\Phi$$

$$\Phi^-$$

$$\Phi \quad \Phi^-$$

$$\Phi$$

$$\Phi^-$$

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3.4 Linear Homogenous Equation with constant Coefficients

Example 3.5

Solution.

$$\phi \quad \phi^- \quad \phi \quad \phi^-$$

Example 3.6

3.4 Linear Homogenous Equation with constant Coefficients

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- - -

3.4 Linear Homogenous Equation with constant Coefficients

$$| - |$$

$$- \pm$$

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$$\Phi \quad \Phi$$

$$\Phi$$

$$\Phi^-$$

$$\Phi \quad \Phi^-$$

$$\Phi \quad \Phi^-$$

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3.5 Characterization of Fundamental Matrix in terms of exponential functions

$$\Phi^{-1}(t) \Phi^{-1}(s) = \Phi^{-1}(s)$$

$$\Phi^{-1}(t) \Phi^{-1}(s) = \Phi^{-1}(s)$$

$$\Phi^{-1}(t) \Phi^{-1}(s) = \Phi^{-1}(s)$$

3.5 Characterization of Fundamental Matrix in terms of exponential functions

x

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3.5 Characterization of Fundamental Matrix in terms of exponential functions

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3.5 Characterization of Fundamental Matrix in terms of exponential functions

Theorem 3.9

Φ //

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Φ

Proposition 3.1

x

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3.5 Characterization of Fundamental Matrix in terms of exponential functions

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x

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Proof.

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3.5 Characterization of Fundamental Matrix in terms of exponential functions

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3.5 Characterization of Fundamental Matrix in terms of exponential functions

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3.7 Linear Homogeneous System with Periodic Coefficients

Proof. $\Phi \quad \Phi$

$$- \Phi \quad \begin{matrix} \dot{\Phi} & \Phi \\ \dot{\Phi} & \Phi \end{matrix} \{ \quad \}$$

$$\dot{\Phi} - \Phi$$

$$- \Phi \quad - \Phi \quad \Phi \quad \Phi \quad \Phi$$

$$\Phi \quad - \Phi \quad \Phi$$

$$\Phi \quad \Phi \quad \Phi$$

$$\Phi \quad - \Phi \quad \Phi$$

■

Example 3.7

3.7 Linear Homogeneous System with Periodic Coefficients

x

Theorem 3.11 $\Phi \quad \Phi$

Ψ

$$\Psi \quad \Phi$$

$$\Phi$$

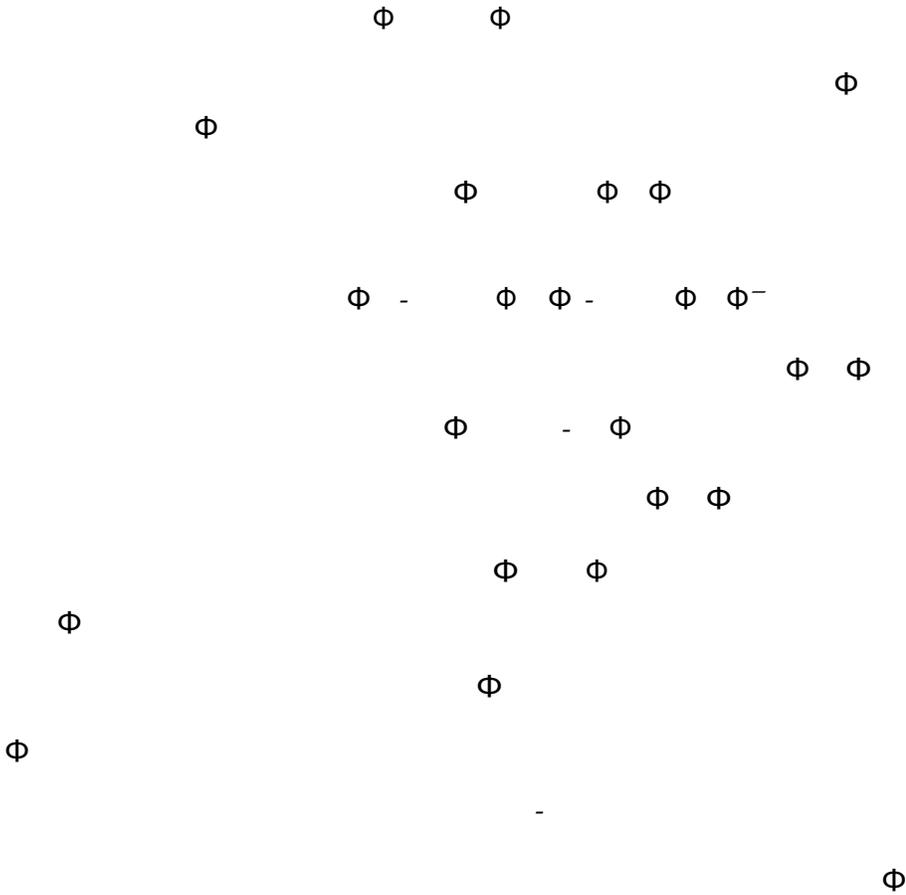
$$\Phi$$

Proof. $\Phi \quad \Phi$

3.6 Linear Nonhomogeneous System

$$- \Phi \quad \Phi$$

4 Conclusion



4 Conclusion

5 Summary

5 Summary

Φ

Φ

Φ

Φ

solution space

linear combination

fundamental matrix

(method of variation of constants)

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x

adjoint

6 Tutor Marked Assignments(TMAs)

Exercise 6.1

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6 Tutor Marked Assignments(TMAs)

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x

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6 Tutor Marked Assignments(TMAs)

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UNIT 5: ADJOINT SYSTEMS

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Introduction

Objectives

The Adjoint Equation

Conclusion

Summary

Tutor Marked Assignments (TMAs)

1 Introduction

2 Objectives

3 The Adjoint Equation

3.1 Definitions and Examples

Definition 3.1

$$L^*y' - M^*y = N^*y$$

adjoint operator

adjoint equation

$$L^*y' - M^*y = N^*y$$

3.1.1 The Second-Order Case

$$L^*y' - M^*y = N^*y$$

3 The Adjoint Equation

Example 3.1

$$\begin{aligned} & \frac{1}{2} \frac{d}{dt} \left(\frac{1}{2} \dot{x}^2 + \frac{1}{2} \dot{y}^2 \right) \\ &= \frac{1}{2} \left(\dot{x} \ddot{x} + \dot{y} \ddot{y} \right) \\ &= \frac{1}{2} \left(-\dot{x} \frac{1}{2} \dot{x} - \dot{y} \frac{1}{2} \dot{y} \right) \\ &= -\frac{1}{4} (\dot{x}^2 + \dot{y}^2) \end{aligned}$$

3.1.2 Lagrange Identity

Theorem 3.1 Lagrange Identity.

$$\begin{aligned} & \frac{d}{dt} \left(\frac{1}{2} \dot{x}^2 + \frac{1}{2} \dot{y}^2 \right) \\ &= \dot{x} \ddot{x} + \dot{y} \ddot{y} \\ &= -\dot{x} \frac{1}{2} \dot{x} - \dot{y} \frac{1}{2} \dot{y} \\ &= -\frac{1}{2} (\dot{x}^2 + \dot{y}^2) \end{aligned}$$

$$\frac{d}{dt} \left(\frac{1}{2} \dot{x}^2 + \frac{1}{2} \dot{y}^2 \right) = -\frac{1}{2} (\dot{x}^2 + \dot{y}^2)$$

Proof.

$$\begin{aligned} & \frac{d}{dt} \left(\frac{1}{2} \dot{x}^2 + \frac{1}{2} \dot{y}^2 \right) \\ &= \dot{x} \ddot{x} + \dot{y} \ddot{y} \\ &= -\dot{x} \frac{1}{2} \dot{x} - \dot{y} \frac{1}{2} \dot{y} \\ &= -\frac{1}{2} (\dot{x}^2 + \dot{y}^2) \end{aligned}$$

3.1 Definitions and Examples

$$\begin{aligned} & \int_{\partial \Omega} u \nu_1 - \int_{\partial \Omega} u \nu_2 \\ & \int_{\partial \Omega} u \nu_3 - \int_{\partial \Omega} u \nu_4 \\ & \int_{\partial \Omega} u \nu_5 - \int_{\partial \Omega} u \nu_6 \\ & \int_{\partial \Omega} u \nu_7 - \int_{\partial \Omega} u \nu_8 \\ & \int_{\partial \Omega} u \nu_9 - \int_{\partial \Omega} u \nu_{10} \\ & \int_{\partial \Omega} u \nu_{11} - \int_{\partial \Omega} u \nu_{12} \\ & \int_{\partial \Omega} u \nu_{13} - \int_{\partial \Omega} u \nu_{14} \\ & \int_{\partial \Omega} u \nu_{15} - \int_{\partial \Omega} u \nu_{16} \\ & \int_{\partial \Omega} u \nu_{17} - \int_{\partial \Omega} u \nu_{18} \\ & \int_{\partial \Omega} u \nu_{19} - \int_{\partial \Omega} u \nu_{20} \end{aligned}$$

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Corollary 3.1 Green's formula

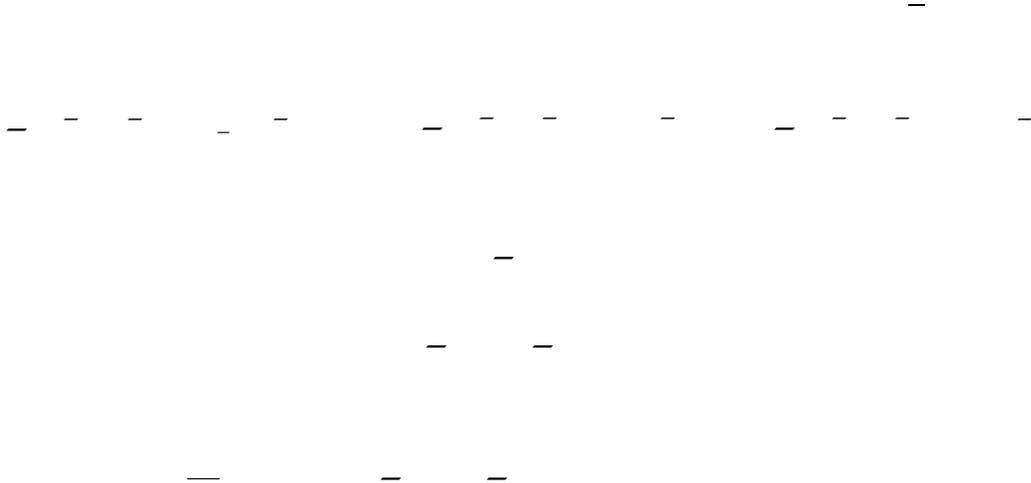
$$\int_{\partial \Omega} u \nu_1 - \int_{\partial \Omega} u \nu_2$$

Proof.

■

The Second-Order Case.

$$\begin{aligned} & \int_{\partial \Omega} u \nu_1 - \int_{\partial \Omega} u \nu_2 \\ & \int_{\partial \Omega} u \nu_3 - \int_{\partial \Omega} u \nu_4 \\ & \int_{\partial \Omega} u \nu_5 - \int_{\partial \Omega} u \nu_6 \\ & \int_{\partial \Omega} u \nu_7 - \int_{\partial \Omega} u \nu_8 \\ & \int_{\partial \Omega} u \nu_9 - \int_{\partial \Omega} u \nu_{10} \\ & \int_{\partial \Omega} u \nu_{11} - \int_{\partial \Omega} u \nu_{12} \\ & \int_{\partial \Omega} u \nu_{13} - \int_{\partial \Omega} u \nu_{14} \\ & \int_{\partial \Omega} u \nu_{15} - \int_{\partial \Omega} u \nu_{16} \\ & \int_{\partial \Omega} u \nu_{17} - \int_{\partial \Omega} u \nu_{18} \\ & \int_{\partial \Omega} u \nu_{19} - \int_{\partial \Omega} u \nu_{20} \end{aligned}$$



Theorem 3.2

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Proof.

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The Second Order Case

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Example 3.2



Solution.

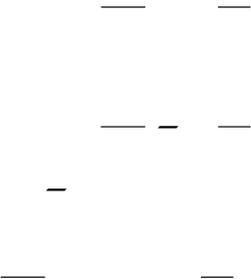


Theorem 3.3

Proof.



Example 3.3



3.2 Self Adjointness

Definition 3.2

self adjoint

Theorem 3.4

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Proof.

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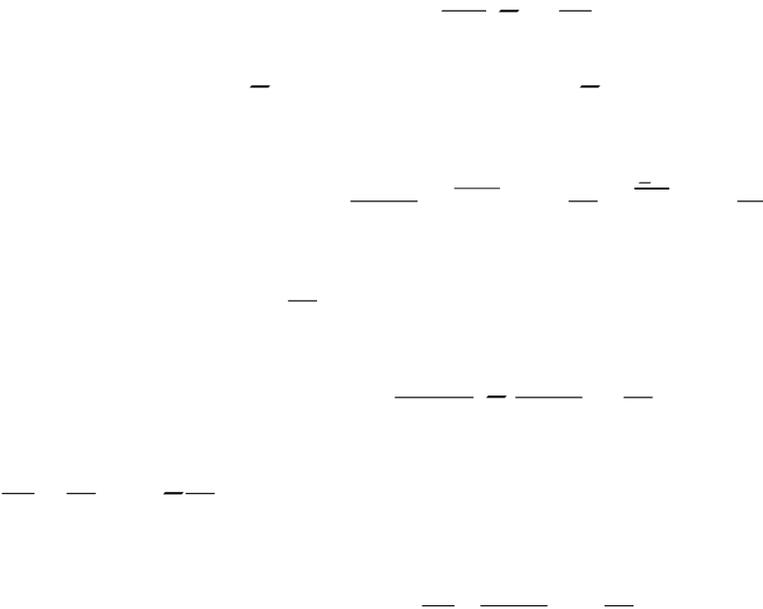
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Corollary 3.2

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Example 3.5



4 Conclusion

5 Summary

6 Tutor Marked Assignments(TMAs)

Exercise 6.1



4 Conclusion

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MODULE 3

UNIT 6: STURM-LIOUVILLE BOUDARY VALUE PROBLEMS

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3.1 Sturm-Liouville Problems

3.1.1 Definition and Examples

Definition 3.1

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Example 3.1

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Example 3.2

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Example 3.3

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Solution.

Case I:

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Case II:

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III:

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Case

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3.1.2 Characteristic Values and Characteristic Functions

Definition 3.2

Characteristic values
characteristic functions

Example 3.4

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Example 3.5

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Solution.

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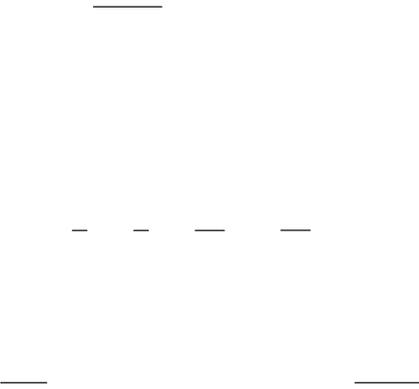
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Theorem 3.1



Example 3.6

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UNIT 7: NONLINEAR EQUATIONS

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3 Main Content

3.1 Phase Plane, Paths, and Critical Points

3.1.1 Basic Concepts and Definitions

3.1 Phase Plane, Paths, and Critical Points

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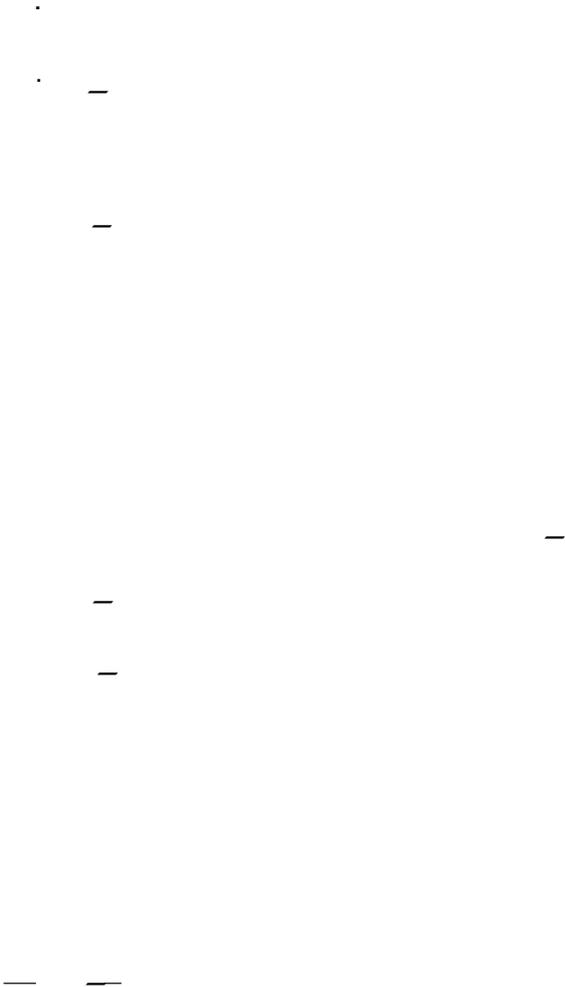
3.1 Phase Plane, Paths, and Critical Points

Definition 3.1

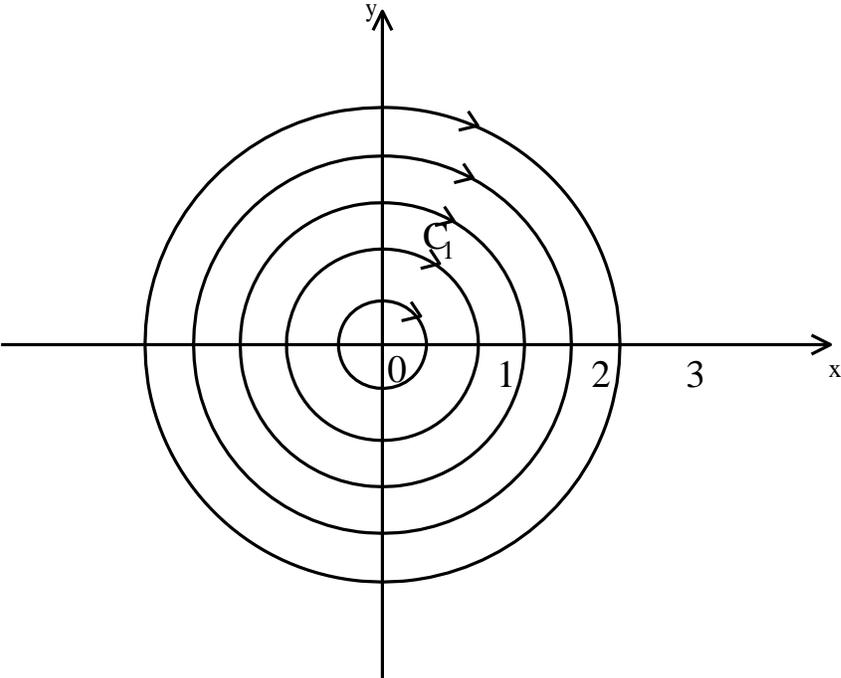
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critical point

Example 3.1



3.1 Phase Plane, Paths, and Critical Points



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Definition 3.2

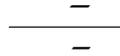
isolated

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3.2 Critical Points and Paths of Linear Systems

Definition 3.3

Definition 3.4



3.1.2 Types of Critical Points

Center:



Saddle point

spiral point



node



3.1.3 Stability

Definition 3.5



stable

3.2 Critical Points and Paths of Linear Systems

3.2.1 Basic Theorems

3.2 Critical Points and Paths of Linear Systems

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Theorem 3.1

point

node

saddle

node

spiral point.

center

Theorem 3.2

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3.3 Critical Points and Paths of Nonlinear Systems

3.2.2 Examples and Applications

Example 3.2

$$\begin{aligned} \dot{x} &= -x \\ \dot{y} &= -y \end{aligned}$$

Solution.

$$\begin{aligned} x &= C_1 e^{-t} \\ y &= C_2 e^{-t} \end{aligned}$$

Example 3.3

$$\begin{aligned} \dot{x} &= x \\ \dot{y} &= -y \end{aligned}$$

Solution.

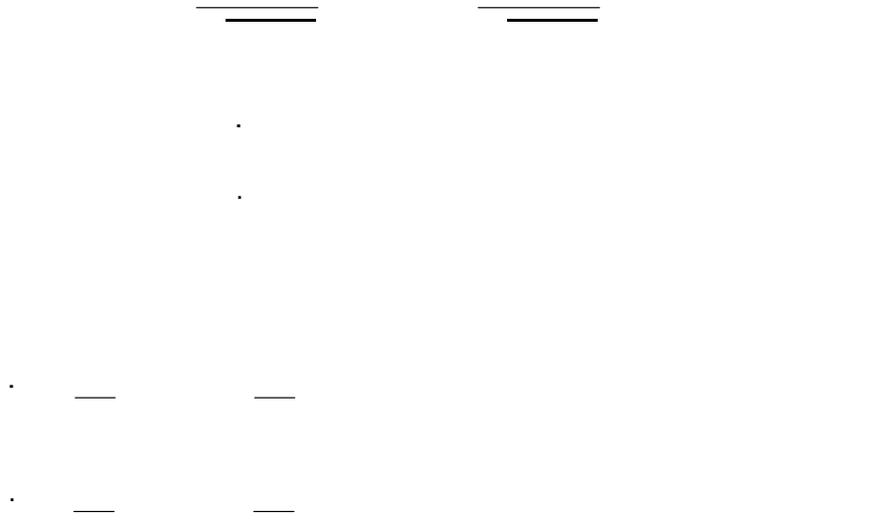
$$\begin{aligned} x &= C_1 e^t \\ y &= C_2 e^{-t} \end{aligned}$$

3.3 Critical Points and Paths of Nonlinear Systems

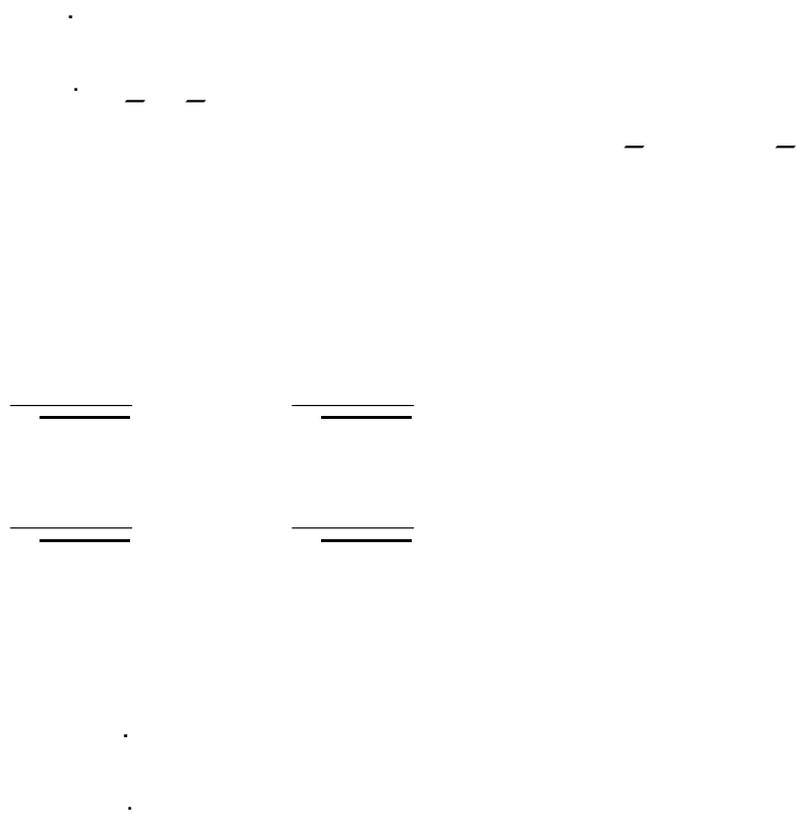
3.3.1 Basic Theorems on Nonlinear Systems

$$\begin{aligned} \dot{x} &= \\ \dot{y} &= \end{aligned}$$

3.3 Critical Points and Paths of Nonlinear Systems



Example 3.4



Theorem 3.3



Theorem 3.4

3.3 Critical Points and Paths of Nonlinear Systems

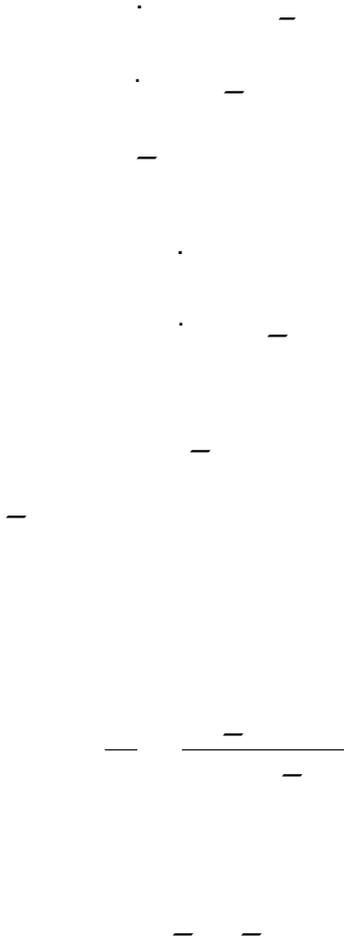
stable

stable

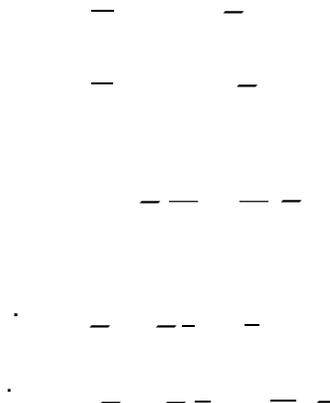
unstable

unstable

Example 3.5



Example 3.6



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Example 3.7

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4 Conclusion

5 Summary

6 Tutor Marked Assignments(TMAs)

Exercise 6.1

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3 Stability

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3.1 Stability in the sense of Lyapunov

Example 3.2

Solution.

$$\begin{aligned}
 & \dot{x} = Ax \\
 & A = \begin{bmatrix} 1 & 0 \\ 0 & -1 \end{bmatrix}
 \end{aligned}$$

Example 3.3

3.1 Stability in the sense of Lyapunov

3.1 Stability in the sense of Lyapunov

Proof.

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$$| - | \text{---} .$$

$$| - | \text{---}$$

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3.2 Quasilinear System

3.2 Quasilinear System

Theorem 3.1

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x

3.3 Lyapunov Second Method

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3.3 Lyapunov Second Method

$$\Omega \{ \quad \}$$

Definitions

$$\Omega \quad \Omega \quad \Omega$$

3.3 Lyapunov Second Method

Example 3.4

Theorem 3.2

Theorem 3.3 Lyapunov

Theorem 3.4

Theorem 3.5 (Cêtaev) On Instability

3.3 Lyapunov Second Method

Example 3.5

Solution.

Example 3.6

Solution.

3.3 Lyapunov Second Method

$$\begin{aligned}
 & \dot{V} = -\dot{x}^2 - \dot{y}^2 - \dot{z}^2 \\
 & \dot{V} = -\dot{x}^2 - \dot{y}^2 - \dot{z}^2 \\
 & \dot{V} = -\dot{x}^2 - \dot{y}^2 - \dot{z}^2 \\
 & \dot{V} = -\dot{x}^2 - \dot{y}^2 - \dot{z}^2
 \end{aligned}$$

Example 3.7

$$\dot{V} = -\dot{x}^2 - \dot{y}^2 - \dot{z}^2$$

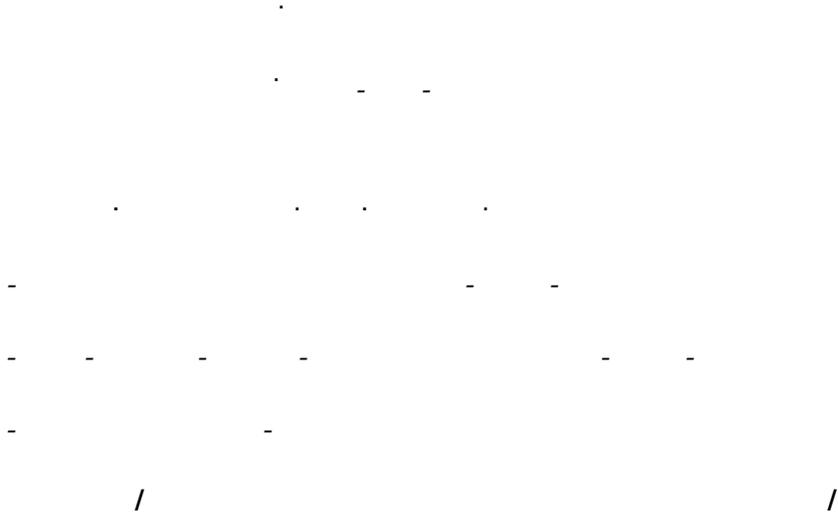
Solution.

$$\begin{aligned}
 & \dot{V} = -\dot{x}^2 - \dot{y}^2 - \dot{z}^2 \\
 & \dot{V} = -\dot{x}^2 - \dot{y}^2 - \dot{z}^2 \\
 & \dot{V} = -\dot{x}^2 - \dot{y}^2 - \dot{z}^2 \\
 & \dot{V} = -\dot{x}^2 - \dot{y}^2 - \dot{z}^2
 \end{aligned}$$

4 Conclusion

Example 3.8

Solution.



4 Conclusion

5 Summary

6 Tutor Marked Assignments(TMAs)

Exercise 6.1

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6 Tutor Marked Assignments (TMAs)
