

K. Eriksson D. Estep C. Johnson

Applied Mathematics: Body and Soul [VOLUME 1]

Derivatives and Geometry in IR3



K. Eriksson • D. Estep • C. Johnson

Applied Mathematics: Body and Soul

[VOLUME 1]

Derivatives and Geometry in IR3



Kenneth Eriksson Claes Johnson Chalmers University of Technology Department of Mathematics 41296 Göteborg, Sweden e-mail: kenneth|claes@math.chalmers.se Donald Estep
Colorado State University
Department of Mathematics
Fort Collins, CO 80523-1874
USA
e-mail: estep@math.colostate.edu

Cataloging-in-Publication Data applied for

A catalog record for this book is available from the Library of Congress.

Bibliographic information published by Die Deutsche Bibliothek Die Deutsche Bibliothek lists this publication in the Deutsche Nationalbibliografie; detailed bibliographic data is available in the Internet at http://dnb.ddb.de.

Mathematics Subject Classification (2000): 15-01, 34-01, 35-01, 49-01, 65-01, 70-01, 76-01

ISBN 3-540-00890-X Springer-Verlag Berlin Heidelberg New York

This work is subject to copyright. All rights are reserved, whether the whole or part of the material is concerned, specifically the rights of translation, reprinting, reuse of illustrations, recitation, broadcasting, reproduction on microfilm or in any other way, and storage in data banks. Duplication of this publication or parts thereof is permitted only under the provisions of the German Copyright Law of September 9, 1965, in its current version, and permission for use must always be obtained from Springer-Verlag. Violations are liable for prosecution under the German Copyright Law.

Springer-Verlag Berlin Heidelberg New York a member of BertelsmannSpringer Science+Business Media GmbH springeronline.com © Springer-Verlag Berlin Heidelberg 2004 Printed in Germany

The use of general descriptive names, registered names, trademarks etc. in this publication does not imply, even in the absence of a specific statement, that such names are exempt from the relevant protective laws and regulations and therefore free for general use.

Cover design: design & production, Heidelberg and Anders Logg, Department of Computational Mathematics, Chalmers University of Technology
Typesetting: Le-TeX Jelonek, Schmidt & Vöckler GbR, Leipzig
Printed on acid-free paper
46/3142ck-543210

Contents Volume 1

D	eriva	tives and Geometry in \mathbb{R}^3	1
1	Wha	t is Mathematics?	3
	1.1	Introduction	3
	1.2	The Modern World	3
	1.3	The Role of Mathematics	6
	1.4	Design and Production of Cars	11
	1.5	Navigation: From Stars to GPS	11
	1.6	Medical Tomography	11
	1.7	Molecular Dynamics and Medical Drug Design	12
	1.8	Weather Prediction and Global Warming	13
	1.9	Economy: Stocks and Options	13
	1.10	Languages	14
	1.11	Mathematics as the Language of Science	15
	1.12	The Basic Areas of Mathematics	16
	1.13	What Is Science?	17
	1.14	What Is Conscience?	17
	1.15	How to View this Book as a Friend	18
2	The	Mathematics Laboratory	21
	2.1	Introduction	21
	2.2	Math Experience	22

XVIII Contents Volume 1

3	Intro	oduction to Modeling	25
	3.1	Introduction	25
	3.2	The Dinner Soup Model	25
	3.3	The Muddy Yard Model	28
	3.4	A System of Equations	29
	3.5	Formulating and Solving Equations	30
,	A 37.	and Chart Calculus Course	99
4		ery Short Calculus Course	33
	4.1	Introduction	33
	$\frac{4.2}{4.2}$	Algebraic Equations	$\frac{34}{24}$
	4.3	Differential Equations	34
	4.4	Generalization	39
	4.5	Leibniz' Teen-Age Dream	41
	4.6	Summary	43
	4.7	Leibniz	44
5	Nati	iral Numbers and Integers	47
	5.1	Introduction	47
	5.2	The Natural Numbers	48
	5.3	Is There a Largest Natural Number?	51
	5.4	The Set \mathbb{N} of All Natural Numbers	52
	5.5	Integers	53
	5.6	Absolute Value and the Distance Between Numbers	56
	5.7	Division with Remainder	57
	5.8	Factorization into Prime Factors	58
	5.9	Computer Representation of Integers	59
c	N/I-41		
O		hematical Induction Induction	63
	6.1	Induction	63
	6.2	Changes in a Population of Insects	68
7	Rati	onal Numbers	71
	7.1	Introduction	71
	7.2	How to Construct the Rational Numbers	72
	7.3	On the Need for Rational Numbers	75
	7.4	Decimal Expansions of Rational Numbers	
	7.5	Periodic Decimal Expansions of Rational Numbers	76
	7.6	Set Notation	80
	7.7	The Set $\mathbb Q$ of All Rational Numbers	81
	7.8	The Rational Number Line and Intervals	82
	7.9	Growth of Bacteria	83
	7.10	Chemical Equilibrium	85

8	Pyth	agoras and Euclid	87
	8.1	Introduction	87
	8.2	Pythagoras Theorem	87
	8.3	The Sum of the Angles of a Triangle is 180°	89
	8.4	Similar Triangles	91
	8.5	When Are Two Straight Lines Orthogonal?	91
	8.6	The GPS Navigator	94
	8.7	Geometric Definition of $\sin(v)$ and $\cos(v)$	96
	8.8	Geometric Proof of Addition Formulas for $\cos(v)$	97
	8.9	Remembering Some Area Formulas	98
	8.10	Greek Mathematics	98
	8.11	The Euclidean Plane \mathbb{Q}^2	99
	8.12	From Pythagoras to Euclid to Descartes	100
	8.13	Non-Euclidean Geometry	101
9	Wha	t is a Function?	103
	9.1	Introduction	103
	9.2	Functions in Daily Life	106
	9.3	Graphing Functions of Integers	109
	9.4	Graphing Functions of Rational Numbers	112
	9.5	A Function of Two Variables	114
	9.6	Functions of Several Variables	116
10	Poly	nomial functions	119
	10.1	Introduction	119
	10.2	Linear Polynomials	120
	10.3	Parallel Lines	124
	10.4	Orthogonal Lines	124
	10.5	Quadratic Polynomials	125
	10.6	Arithmetic with Polynomials	129
	10.7	Graphs of General Polynomials	135
	10.8	Piecewise Polynomial Functions	137
	Com	binations of functions	141
11	11.1		141
	11.1	Sum of Two Eupations and Bradust	141
	11.2		142
	11.9	of a Function with a Number	
		Multiplication and Division of Functions	$\frac{143}{143}$
	11.5	Rational Functions	
	11.6	The Composition of Functions	145
12	Lips	chitz Continuity	149
	12.1	Introduction	149
	12.2	The Lipschitz Continuity of a Linear Function	150

	12.3	The Definition of Lipschitz Continuity	151
	12.4	Monomials	154
	12.5	Linear Combinations of Functions	157
	12.6	Bounded Functions	158
	12.7	The Product of Functions	159
	12.8	The Quotient of Functions	160
	12.9	The Composition of Functions	161
	12.10	Functions of Two Rational Variables	162
	12.11	Functions of Several Rational Variables	163
13	Seau	ences and limits	165
	13.1	A First Encounter with Sequences and Limits	165
	13.2	Socket Wrench Sets	167
	13.3	J.P. Johansson's Adjustable Wrenches	169
	13.4	The Power of Language:	
		From Infinitely Many to One	169
	13.5	The $\epsilon - N$ Definition of a Limit	170
	13.6	A Converging Sequence Has a Unique Limit	174
	13.7	Lipschitz Continuous Functions and Sequences	175
	13.8	Generalization to Functions of Two Variables	176
	13.9	Computing Limits	177
	13.10	Computer Representation of Rational Numbers	180
		Sonya Kovalevskaya	181
			105
14		Square Root of Two	185
		Introduction	185
	$\frac{14.2}{14.2}$	$\sqrt{2}$ Is Not a Rational Number!	187
	$\frac{14.3}{14.4}$	Computing $\sqrt{2}$ by the Bisection Algorithm	188
	14.4	The Bisection Algorithm Converges!	189
	$\frac{14.5}{14.6}$	First Encounters with Cauchy Sequences	192
	14.6	Computing $\sqrt{2}$ by the Deca-section Algorithm	192
15	Real	numbers	195
	15.1	Introduction	195
	15.2	Adding and Subtracting Real Numbers	197
	15.3	Generalization to $f(x, \bar{x})$ with f Lipschitz	199
	15.4	Multiplying and Dividing Real Numbers	200
	15.5	The Absolute Value	200
	15.6	Comparing Two Real Numbers	200
	15.7	Summary of Arithmetic with Real Numbers	201
	15.8	Why $\sqrt{2}\sqrt{2}$ Equals 2	201
	15.9	A Reflection on the Nature of $\sqrt{2}$	202
	15.10	Cauchy Sequences of Real Numbers	203
	15.11	Extension from $f: \mathbb{Q} \to \mathbb{Q}$ to $f: \mathbb{R} \to \mathbb{R}$	204
	15.12	Lipschitz Continuity of Extended Functions	205

	15.13	Graphing Functions $f: \mathbb{R} \to \mathbb{R}$	206
		Extending a Lipschitz Continuous Function	206
	15.15	Intervals of Real Numbers	207
	15.16	What Is $f(x)$ if x Is Irrational?	208
		Continuity Versus Lipschitz Continuity	211
16	The l	Bisection Algorithm for $f(x) = 0$	215
	16.1	Bisection	215
	16.2	An Example	217
	16.3	Computational Cost	219
17	Do M	Iathematicians Quarrel?*	22 1
		Introduction	221
	17.2	The Formalists	224
	17.2		$\frac{224}{224}$
	17.4	The Logicists and Set Theory	227
	17.4 17.5		229
		The Peano Axiom System for Natural Numbers	229
	17.6	Real Numbers	
	17.7	Cantor Versus Kronecker	230
	17.8	Deciding Whether a Number is Rational or Irrational.	232
	17.9	The Set of All Possible Books	233
		Recipes and Good Food	234
		The "New Math" in Elementary Education	234
		The Search for Rigor in Mathematics	235
		A Non-Constructive Proof	236
	17.14	Summary	237
18	The l	Function $y = x^r$	241
	18.1	The Function \sqrt{x}	241
	18.2	Computing with the Function \sqrt{x}	242
	18.3	Is \sqrt{x} Lipschitz Continuous on \mathbb{R}^+ ?	242
	18.4	The Function x^r for Rational $r = \frac{p}{q} \dots \dots \dots$	243
	18.5	Computing with the Function x^r ,	243
	18.6	Generalizing the Concept of Lipschitz Continuity	243
	18.7	Turbulent Flow is Hölder (Lipschitz) Continuous with Ex-	
	20.7	ponent $\frac{1}{3}$	244
		<u>*************************************</u>	
19	Fixed	l Points and Contraction Mappings	245
	19.1	Introduction	245
	19.2	Contraction Mappings	246
	19.3	Rewriting $f(x) = 0$ as $x = g(x)$	247
	19.4	Card Sales Model	248
	19.5	Private Economy Model	249
	19.6	Fixed Point Iteration in the Card Sales Model	250
	19.7	A Contraction Mapping Has a Unique Fixed Point	254

XXII Contents Volume 1

	19.8	Generalization to $g:[a,b] \rightarrow [a,b]$	256
	19.9	Linear Convergence in Fixed Point Iteration	257
	19.10	Quicker Convergence	258
		Quadratic Convergence	259
	_		
20	Analy	vtic Geometry in \mathbb{R}^2	265
	20.1	Introduction	265
	20.2	Descartes, Inventor of Analytic Geometry	266
	20.3	Descartes: Dualism of Body and Soul	266
	20.4	The Euclidean Plane \mathbb{R}^2	267
	20.5	Surveyors and Navigators	269
	20.6	A First Glimpse of Vectors	270
	20.7	Ordered Pairs as Points or Vectors/Arrows	271
	20.8	Vector Addition	272
	20.9	Vector Addition and the Parallelogram Law	273
		Multiplication of a Vector by a Real Number	274
		The Norm of a Vector	275
		Polar Representation of a Vector	275
		Standard Basis Vectors	277
		Scalar Product	278
		Properties of the Scalar Product	278
		Geometric Interpretation of the Scalar Product	279
		Orthogonality and Scalar Product	280
		Projection of a Vector onto a Vector	281
		Rotation by 90°	283
		Rotation by an Arbitrary Angle θ	285
		Rotation by θ Again!	286
		Rotating a Coordinate System	286
		Vector Product	287
		The Area of a Triangle with a Corner at the Origin	<u>290</u>
		The Area of a General Triangle	290
	20.26	The Area of a Parallelogram Spanned	
		by Two Vectors	291
		Straight Lines	292
		Projection of a Point onto a Line	294
		When Are Two Lines Parallel?	294
	20.30	A System of Two Linear Equations	
		in Two Unknowns	295
		Linear Independence and Basis	297
		The Connection to Calculus in One Variable	298
		Linear Mappings $f: \mathbb{R}^2 \to \mathbb{R}$	299
		Linear Mappings $f: \mathbb{R}^2 \to \mathbb{R}^2$	299
		Linear Mappings and Linear Systems of Equations	300
		A First Encounter with Matrices	300
	20.37	First Applications of Matrix Notation	302

		Quadratic Approximation	384
	24.9	The Derivative of an Inverse Function	387
	24.10	Implicit Differentiation	388
	24.11	Partial Derivatives	389
	24.12	A Sum Up So Far	390
2 5	Newt	on's Method	393
	25.1	Introduction	393
	25.2	Convergence of Fixed Point Iteration	393
	25.3	Newton's Method	394
	25.4	Newton's Method Converges Quadratically	395
	25.5	A Geometric Interpretation of Newton's Method	396
	25.6	What Is the Error of an Approximate Root?	397
	25.7	Stopping Criterion	400
	25.8	Globally Convergent Newton Methods	400
26	Calil	eo, Newton, Hooke, Malthus and Fourier	403
<u> 20</u>		Introduction	403 403
	26.2	Newton's Law of Motion	404
	26.3	Galileo's Law of Motion	404
	26.4	Hooke's Law	407
	26.5	Newton's Law plus Hooke's Law	408
	26.6	Fourier's Law for Heat Flow	409
	26.7	Newton and Rocket Propulsion	410
	26.8	Malthus and Population Growth	412
	26.9	Einstein's Law of Motion	413
		Summary	414
	20.10	Dummary	414
	Refer	ences	417
	Index		419

Contents Volume 1 XXV

419

Contents Volume 2

tegra	us and Geometry in K"	427
The l	Integral	429
27.1	Primitive Functions and Integrals	429
27.2	Primitive Function of $f(x) = x^m$ for $m = 0, 1, 2,$.	433
27.3	Primitive Function of $f(x) = x^m$ for $m = -2, -3, \dots$.	434
27.4	Primitive Function of $f(x) = x^r$ for $r \neq -1$	434
27.5	A Quick Overview of the Progress So Far	435
27.6	A "Very Quick Proof" of the Fundamental Theorem .	435
27.7	A "Quick Proof" of the Fundamental Theorem	437
27.8	A Proof of the Fundamental Theorem of Calculus	438
27.9	Comments on the Notation	444
27.10	Alternative Computational Methods	445
27.11	The Cyclist's Speedometer	445
27.12	Geometrical Interpretation of the Integral	446
27.13	The Integral as a Limit of Riemann Sums	448
27.14	An Analog Integrator	449
Prop	erties of the Integral	453
28.1	Introduction	453
28.2	Reversing the Order of Upper and Lower Limits	454
28.3	The Whole Is Equal to the Sum of the Parts	454
	The 27.1 27.2 27.3 27.4 27.5 27.6 27.7 27.8 27.10 27.11 27.12 27.13 27.14 Prop 28.1 28.2	27.2 Primitive Function of $f(x) = x^m$ for $m = 0, 1, 2,$. 27.3 Primitive Function of $f(x) = x^m$ for $m = -2, -3,$. 27.4 Primitive Function of $f(x) = x^r$ for $r \neq -1$ 27.5 A Quick Overview of the Progress So Far 27.6 A "Very Quick Proof" of the Fundamental Theorem. 27.7 A "Quick Proof" of the Fundamental Theorem 27.8 A Proof of the Fundamental Theorem of Calculus 27.9 Comments on the Notation 27.10 Alternative Computational Methods 27.11 The Cyclist's Speedometer 27.12 Geometrical Interpretation of the Integral 27.13 The Integral as a Limit of Riemann Sums 27.14 An Analog Integrator 27.15 Properties of the Integral 28.1 Introduction 28.2 Reversing the Order of Upper and Lower Limits

XXVIII Contents Volume 2

	28.4	Integrating Piecewise Lipschitz	
		Continuous Functions	455
	28.5	Linearity	456
	28.6	Monotonicity	457
	28.7	The Triangle Inequality for Integrals	457
	28.8	Differentiation and Integration	
		are Inverse Operations	458
	28.9	Change of Variables or Substitution	459
	28.10	Integration by Parts	461
	28.11	The Mean Value Theorem	462
	28.12	Monotone Functions and the Sign of the Derivative	464
	28.13	A Function with Zero Derivative is Constant	464
	28.14	A Bounded Derivative Implies Lipschitz Continuity	465
	28.15	Taylor's Theorem	465
	28.16	October 29, 1675	468
	28.17	The Hodometer	469
00	ml I		450
29		Logarithm $\log(x)$	473
		The Definition of $\log(x)$	473
		The Importance of the Logarithm	474
	29.3	Important Properties of $\log(x)$	475
3 0	Nume	erical Quadrature	479
••	30.1	Computing Integrals	479
		The Integral as a Limit of Riemann Sums	483
		The Midpoint Rule	484
	30.4	Adaptive Quadrature	485
31	The I	Exponential Function $\exp(x) = e^x$	491
	31.1	Introduction	491
	31.2	Construction of the Exponential $\exp(x)$ for $x \geq 0$	493
	31.3	Extension of the Exponential $\exp(x)$ to $x < 0$	498
	31.4	The Exponential Function $\exp(x)$ for $x \in \mathbb{R}$	498
	31.5	An Important Property of $\exp(x)$	499
	31.6	The Inverse of the Exponential is the Logarithm	500
	31.7	The Function a^x with $a > 0$ and $x \in \mathbb{R}$	501
ขา	Trigo	nometric Functions	505
JZ		The Defining Differential Equation	505
	$\frac{32.1}{32.2}$	Trigonometric Identities	509
	$\frac{32.2}{32.3}$	The Functions $tan(x)$ and $cot(x)$ and Their Derivatives	510
	32.4	Inverses of Trigonometric Functions	
			<u>511</u>
	$\frac{32.5}{32.6}$	The Functions $\sinh(x)$ and $\cosh(x)$	513 514
	$\frac{32.6}{22.7}$	The Hanging Chain	514
	32.7	Comparing $u'' + k^2 u(x) = 0$ and $u'' - k^2 u(x) = 0$	515

33	The	Functions $\exp(z)$, $\log(z)$, $\sin(z)$ and $\cos(z)$ for $z \in \mathbb{C}$	517
	33.1	Introduction	517
	33.2	Definition of $\exp(z)$	517
	33.3	Definition of $\sin(z)$ and $\cos(z)$	518
	33.4	de Moivres Formula	518
	33.5	Definition of $\log(z)$	519
		niques of Integration	52 1
	34.1	Introduction	521
	34.2	Rational Functions: The Simple Cases	522
	34.3	Rational Functions: Partial Fractions	523
	34.4	Products of Polynomial and Trigonometric	
		or Exponential Functions	52 8
	34.5	Combinations of Trigonometric and Root Functions	528
	34.6	Products of Exponential and Trigonometric Functions	52 9
	34.7	Products of Polynomials and Logarithm Functions	529
35	Solv	ing Differential Equations Using the Exponential	531
	35.1	Introduction	531
	35.2	Generalization to $u'(x) = \lambda(x)u(x) + f(x)$	$\frac{531}{532}$
	35.3	The Differential Equation $u''(x) - u(x) = 0$	$\frac{532}{536}$
	$\frac{35.4}{35.4}$	The Differential Equation $\sum_{i=0}^{n} a_i D^k u(x) = 0$	537
	35.5	The Differential Equation $\sum_{k=0}^{n} a_k D^k u(x) = 0$ The Differential Equation $\sum_{k=0}^{n} a_k D^k u(x) = f(x)$	538
	35.6	Euler's Differential Equation	539
	00.0	Edici 5 Differential Equation	000
36	Imp	roper Integrals	541
	36.1	Introduction	541
	36.2	Integrals Over Unbounded Intervals	541
	36.3	Integrals of Unbounded Functions	543
	Serie		547
	37.1	Introduction	547
	37.2	Definition of Convergent Infinite Series	548
	37.3	Positive Series	549
	37.4	Absolutely Convergent Series	552
	37.5	Alternating Series	552
	37.6	The Series $\sum_{i=1}^{\infty} \frac{1}{i}$ Theoretically Diverges!	553
	37.7	Abel	555
	37.8	Galois	556
38	Scale	ar Autonomous Initial Value Problems	EEO
	38.1		559
	38.2	Introduction	559
	38.3	An Analytical Solution Formula	560
	σ		563

39 S	eparable Scalar Initial Value Problems	567
_39	9.1 Introduction	567
39	9.2 An Analytical Solution Formula	56 8
39	9.3 Volterra-Lotka's Predator-Prey Model	57 0
39	9.4 A Generalization	571
40 T	he General Initial Value Problem	57 5
40	0.1 Introduction	575
40	0.2 Determinism and Materialism	577
40	0.3 Predictability and Computability	577
40	0.4 Construction of the Solution	579
40	0.5 Computational Work	580
40	0.6 Extension to Second Order Initial Value Problems	581
40	0.7 Numerical Methods	582
41 C	alculus Tool Bag I	585
	1.1 Introduction	585
	1.2 Rational Numbers	585
	1.3 Real Numbers. Sequences and Limits	586
	1.4 Polynomials and Rational Functions	586
41	1.5 Lipschitz Continuity	587
41	l.6 Derivatives	587
41	1.7 Differentiation Rules	587
41	1.8 Solving $f(x) = 0$ with $f: \mathbb{R} \to \mathbb{R}$	588
41	1.9 Integrals	589
41	1.10 The Logarithm	590
	1.11 The Exponential	591
	1.12 The Trigonometric Functions	591
	1.13 List of Primitive Functions	594
	1.14 Series	594
	1.15 The Differential Equation $\dot{u} + \lambda(x)u(x) = f(x)$	595
	1.16 Separable Scalar Initial Value Problems	595
40 A		507
	nalytic Geometry in \mathbb{R}^n	597
	2.1 Introduction and Survey of Basic Objectives	597
	2.2 Body/Soul and Artificial Intelligence	600
	2.3 The Vector Space Structure of \mathbb{R}^n	600
	2.4 The Scalar Product and Orthogonality	601
	2.5 Cauchy's Inequality	602
	2.6 The Linear Combinations of a Set of Vectors	603
	2.7 The Standard Basis	604
	2.8 Linear Independence	605
	2.9 Reducing a Set of Vectors to Get a Basis	606
	2.10 Using Column Echelon Form to Obtain a Basis	607
42	2.11 Using Column Echelon Form to Obtain $R(A)$	608

44	Solvi	ng Linear Algebraic Systems	651
	44.1	Introduction	651
	44.2	Direct Methods	651
	44.3	Direct Methods for Special Systems	658
	44.4	Iterative Methods	661
	44.5	Estimating the Error of the Solution	671
	44.6	The Conjugate Gradient Method	674
	44.7	GMRES	676
45	Linea	r Algebra Tool Bag	685
		Linear Algebra in \mathbb{R}^2	685
		Linear Algebra in \mathbb{R}^3	686
	45.3	Linear Algebra in \mathbb{R}^n	686
	45.4	Linear Transformations and Matrices	687
	45.5	The Determinant and Volume	688
	45.6	Cramer's Formula	688
	45.7	Inverse	689
	45.8	Projections	689
	45.9	The Fundamental Theorem of Linear Algebra	689
	45.10	The QR-Decomposition	689
		Change of Basis	690
		The Least Squares Method	690
		Eigenvalues and Eigenvectors	690
		The Spectral Theorem	690
		The Conjugate Gradient Method for $Ax = b \dots$.	690
46	The I	Matrix Exponential $\exp(xA)$	691
	46.1	Computation of $\exp(xA)$ when A Is Diagonalizable	692
	46.2	Properties of $\exp(Ax)$	694
	46.3	Duhamel's Formula	694
47	Lagra	ange and the Principle of Least Action*	697
	47.1	Introduction	697
	47.2	A Mass-Spring System	699
		A Pendulum with Fixed Support	700
	47.4	A Pendulum with Moving Support	701
	47.5	The Principle of Least Action	701
	47.6	Conservation of the Total Energy	703
	47.7	The Double Pendulum	703
	47.8	The Two-Body Problem	704
	47.9	Stability of the Motion of a Pendulum	705
	11.0	Stability of the motion of a fundament in the first	100

XXXIV	Contents Volume 2	
53.5	The Discrete System of Equations	762
53.6	Handling Different Boundary Conditions	765
53.7	Error Estimates and Adaptive Error Control	768
53.8	Discretization of Time-Dependent	
	Reaction-Diffusion-Convection Problems	77 3

References	
rterences	

53.9 Non-Linear Reaction-Diffusion-Convection Problems .

Index 779

773

Contents Volume 3

C	alculı	us in Several Dimensions	787
54	Vecto	or-Valued Functions of Several Real Variables	789
	54.1	Introduction	789
	54.2	Curves in \mathbb{R}^n	790
	54.3	Different Parameterizations of a Curve	7 91
	54.4	Surfaces in \mathbb{R}^n , $n \geq 3$	792
	54.5	Lipschitz Continuity	792
	54.6	Differentiability: Jacobian, Gradient and Tangent	794
	54.7	The Chain Rule	798
	54.8	The Mean Value Theorem	799
	54.9	Direction of Steepest Descent and the Gradient	800
	54.10	A Minimum Point Is a Stationary Point	802
	54.11	The Method of Steepest Descent	802
	54.12	Directional Derivatives	803
	54.13	Higher Order Partial Derivatives	804
		Taylor's Theorem	805
	54.15	The Contraction Mapping Theorem	806
	54.16	Solving $f(x) = 0$ with $f: \mathbb{R}^n \to \mathbb{R}^n$	808
	54.17	The Inverse Function Theorem	809
	54.18	The Implicit Function Theorem	810
	54.19	Newton's Method	811
	54.20	Differentiation Under the Integral Sign	812

XXXVI Contents Volume 3

55	Level	Curves/Surfaces and the Gradient	815
	55.1	Level Curves	815
	55.2	Local Existence of Level Curves	817
	55.3	Level Curves and the Gradient	817
	55.4	Level Surfaces	818
	55.5	Local Existence of Level Surfaces	819
	55.6	Level Surfaces and the Gradient	819
56	Linea	rization and Stability of Initial Value Problems	823
	56.1	Introduction	823
	56.2	Stationary Solutions	824
	56.3	Linearization at a Stationary Solution	824
	56.4	Stability Analysis when $f'(\bar{u})$ Is Symmetric	825
	56.5	Stability Factors	826
	56.6	Stability of Time-Dependent Solutions	829
	56.7	Sum Up	829
57	Adap	tive Solvers for IVPs	831
	57.1	Introduction	831
	57.2	The $cG(1)$ Method	832
	57.3	Adaptive Time Step Control for $cG(1)$	834
	57.4	Analysis of cG(1) for a Linear Scalar IVP	834
	57.5	Analysis of cG(1) for a General IVP	837
	57.6	Analysis of Backward Euler for a General IVP	838
	57.7	Stiff Initial Value Problems	840
	57.8	On Explicit Time-Stepping for Stiff Problems	842
58	Loren	z and the Essence of Chaos*	849
	58.1	Introduction	849
	58.2	The Lorenz System	850
	58.3	The Accuracy of the Computations	852
	58.4	Computability of the Lorenz System	854
	58.5	The Lorenz Challenge	856
59	The S	Solar System*	859
	59.1	Introduction	859
	59.2	Newton's Equation	862
	59.3	Einstein's Equation	863
	59.4	The Solar System as a System of ODEs	864
	59.5	Predictability and Computability	867
	59.6	Adaptive Time-Stepping	868
	59.7	Limits of Computability and Predictability	869

_ 00 Օիս	mization	<u>87</u> 1
60.1	Introduction	87 1
60.2	Sorting if Ω Is Finite	87 2
_60.3	What if Ω Is Not Finite?	87 3
-60.4	Existence of a Minimum Point	87 4
-60.5	The Derivative Is Zero at an Interior Minimum Point .	87 4
60.6	The Role of the Hessian	878
60.7	Minimization Algorithms: Steepest Descent	87 8
60.8	Existence of a Minimum Value and Point	87 9
_60.9	Existence of Greatest Lower Bound	881
60.10	Constructibility of a Minimum Value and Point	882
60.11	A Decreasing Bounded Sequence Converges!	882
61 The	Divergence Betation and Laplacian	005
	Divergence, Rotation and Laplacian	<u>88</u> 5
61.1	Introduction	<u>88</u> 5
_61.2		886
61.3	The Laplacian in Polar Coordinates	<u>88</u> 7
61.4	Some Basic Examples	<u>888</u>
61.5	The Laplacian Under Rigid Coordinate Transformations	<u>888</u>
61.6	The Case of \mathbb{R}^3	889
61.7	Basic Examples, Again	<u>89</u> 0
61.8	The Laplacian in Spherical Coordinates	<u>89</u> 1
62 Mete	eorology and Coriolis Forces*	89 3
	eorology and Coriolis Forces* Introduction	893 893
-62.1		89 3
-62.1	Introduction	89 3
62.1 62.2 62.3	A Basic Meteorological Model	893 894 895
62.1 62.2 62.3	Introduction	893 894 895 899
62.1 62.2 62.3 63 Curv 63.1	Introduction	893 894 895 899 899
62.1 62.2 62.3 63.1 63.2	Introduction	893 894 895 899 899
62.1 62.2 62.3 63.1 63.2 63.3	$ \begin{array}{cccccccccccccccccccccccccccccccccccc$	893 894 895 899 899 899 901
62.1 62.2 62.3 63.1 63.2 63.3 63.4	$ \begin{array}{cccccccccccccccccccccccccccccccccccc$	893 894 895 899 899 899 901 902
62.1 62.2 62.3 63.1 63.2 63.3 63.4 63.5	$\begin{array}{c} \textbf{Introduction} \\ \textbf{A Basic Meteorological Model} \\ \textbf{Rotating Coordinate Systems and Coriolis Acceleration} \\ \hline \textbf{e Integrals} \\ \hline \textbf{Introduction} \\ \textbf{The Length of a Curve in } \mathbb{R}^2 \\ \hline \textbf{Curve Integral} \\ \textbf{Reparameterization} \\ \hline \textbf{Work and Line Integrals} \\ \hline \end{array}$	893 894 895 899 899 899 901 902 903
62.1 62.2 62.3 63.1 63.2 63.3 63.4 63.5 63.6	$\begin{array}{cccccccccccccccccccccccccccccccccccc$	893 894 895 899 899 899 901 902 903 904
62.1 62.2 62.3 63.1 63.2 63.3 63.4 63.5 63.6 63.7	Introduction A Basic Meteorological Model Rotating Coordinate Systems and Coriolis Acceleration The Introduction The Length of a Curve in \mathbb{R}^2 Curve Integral Reparameterization Work and Line Integrals Work and Gradient Fields Using the Arclength as a Parameter	893 894 895 899 899 901 902 903 904 905
62.1 62.2 62.3 63.1 63.2 63.3 63.4 63.5 63.6 63.7 63.8	Introduction A Basic Meteorological Model Rotating Coordinate Systems and Coriolis Acceleration The Introduction The Length of a Curve in \mathbb{R}^2 Curve Integral Reparameterization Work and Line Integrals Work and Gradient Fields Using the Arclength as a Parameter The Curvature of a Plane Curve	893 894 895 899 899 901 902 903 904 905 906
62.1 62.2 62.3 63.1 63.2 63.3 63.4 63.5 63.6 63.7	Introduction A Basic Meteorological Model Rotating Coordinate Systems and Coriolis Acceleration The Introduction The Length of a Curve in \mathbb{R}^2 Curve Integral Reparameterization Work and Line Integrals Work and Gradient Fields Using the Arclength as a Parameter	893 894 895 899 899 901 902 903 904 905
62.1 62.2 62.3 63.1 63.2 63.3 63.4 63.5 63.6 63.7 63.8 63.9	Introduction A Basic Meteorological Model Rotating Coordinate Systems and Coriolis Acceleration The Introduction The Length of a Curve in \mathbb{R}^2 Curve Integral Reparameterization Work and Line Integrals Work and Gradient Fields Using the Arclength as a Parameter The Curvature of a Plane Curve	893 894 895 899 899 901 902 903 904 905 906
62.1 62.2 62.3 63.1 63.2 63.3 63.4 63.5 63.6 63.7 63.8 63.9	Introduction	893 894 895 899 899 901 902 903 904 905 906 907
62.1 62.2 62.3 63.1 63.2 63.3 63.4 63.5 63.6 63.7 63.8 63.9	Introduction	893 894 895 899 899 899 901 902 903 904 905 906 907
62.1 62.2 62.3 63 Curv 63.1 63.2 63.3 63.4 63.5 63.6 63.7 63.8 63.9	Introduction	893 894 895 899 899 899 901 902 903 904 905 906 907
62.1 62.2 62.3 63.1 63.2 63.3 63.4 63.5 63.6 63.7 63.8 63.9 64.1 64.1 64.2	Introduction	893 894 895 899 899 901 902 903 904 905 906 907 911 911 912

71	Cent	er of Mass and Archimedes' Principle*	977
	71.1	Introduction	977
	71.2	Center of Mass	978
	71.3	Archimedes' Principle	981
	71.4	Stability of Floating Bodies	983
72	Newt	on's Nightmare*	987
73	Lapla	cian Models	993
	73.1		993
	73.2	Heat Conduction	993
	73.3	The Heat Equation	996
	73.4	Stationary Heat Conduction: Poisson's Equation	997
	73.5	•	999
	73.6	Elastic Membrane	
	73.7	Solving the Poisson Equation	1001
	73.8	The Wave Equation: Vibrating Elastic Membrane	1003
	73.9	Fluid Mechanics	
	73.10	Maxwell's Equations	1009
		Gravitation	1013
		The Eigenvalue Problem for the Laplacian	1017
		Quantum Mechanics	1019
74		nical Reactions*	1005
14	74.1		1025 1025
		Variable Temperature	$\frac{1025}{1028}$
		Variable Temperature	
	14.5	Space Dependence	1028
75	Calcu	ılus Tool Bag II	1031
	75.1	Introduction	1031
	75.2	Lipschitz Continuity	1031
	75.3	Differentiability	1031
	75.4	The Chain Rule	1032
	75.5	Mean Value Theorem for $f: \mathbb{R}^n \to \mathbb{R}$	1032
	75.6	A Minimum Point Is a Stationary Point	1032
	75.7	Taylor's Theorem	1032
	75.8	Contraction Mapping Theorem	1033
	75.9	Inverse Function Theorem	1033
	75.10	Implicit Function Theorem	1033
	75.11	Newton's Method	1033
	75.12	Differential Operators	1033
		Curve Integrals	1034
		Multiple Integrals	1035
		Surface Integrals	1035
		Green's and Gauss' Formulas	1036
		Stokes' Theorem	

	00.4	$\nabla P = P \cdot T + P + P \cdot P$	1000
	80.4	The Differential Equation $\sum_{k=0}^{n} a_k D^k u(x) = 0$	1098
	80.5	The Damped Linear Oscillator	1099
	80.6	The Matrix Exponential	1099
	80.7	Fundamental Solutions of the Laplacian	1100
	80.8	The Wave Equation in 1d	1100
	80.9	Numerical Methods for IVPs	1100
	80.10	cg(1) for Convection-Diffusion-Reaction	1101
		Svensson's Formula for Laplace's Equation	1101
		Optimal Control	1101
<u>81</u>		ications Tool Bag	1103
		Introduction	-1103
	81.2	Malthus' Population Model	1103
	81.3	The Logistics Equation	1103
	81.4	Mass-Spring-Dashpot System	1103
	81.5	LCR-Circuit	1104
	81.6	Laplace's Equation for Gravitation	1104
	81.7	The Heat Equation	1104
	81.8	The Wave Equation	1104
	81.9	Convection-Diffusion-Reaction	1104
	81.10	Maxwell's Equations	1105
		The Incompressible Navier-Stokes Equations	1105
		Schrödinger's Equation	1105
		6	
82	-	ytic Functions	1107
	82.1	The Definition of an Analytic Function	1107
	82.2	The Derivative as a Limit of Difference Quotients	1109
	82.3	Linear Functions Are Analytic	1109
	82.4	The Function $f(z) = z^2$ Is Analytic	1109
	82.5	The Function $f(z) = z^n$ Is Analytic for $n = 1, 2,$.	1110
	82.6	Rules of Differentiation	1110
	82.7	The Function $f(z) = z^{-n}$	1110
	82.8		
	04.0	The Cauchy-Riemann Equations	1110
	82.9	The Cauchy-Riemann Equations	
	82.9	The Cauchy-Riemann Equations and the Derivative	1112
	82.9 82.10	The Cauchy-Riemann Equations and the Derivative The Cauchy-Riemann Equations in Polar Coordinates	1112 1113
	82.9 82.10 82.11	The Cauchy-Riemann Equations and the Derivative The Cauchy-Riemann Equations in Polar Coordinates The Real and Imaginary Parts of an Analytic Function	1112 1113 1113
	82.9 82.10 82.11 82.12	The Cauchy-Riemann Equations and the Derivative The Cauchy-Riemann Equations in Polar Coordinates The Real and Imaginary Parts of an Analytic Function Conjugate Harmonic Functions	1112 1113 1113 1113
	82.9 82.10 82.11 82.12 82.13	The Cauchy-Riemann Equations and the Derivative The Cauchy-Riemann Equations in Polar Coordinates The Real and Imaginary Parts of an Analytic Function Conjugate Harmonic Functions	1112 1113 1113 1113 1114
	82.9 82.10 82.11 82.12 82.13 82.14	The Cauchy-Riemann Equations and the Derivative The Cauchy-Riemann Equations in Polar Coordinates The Real and Imaginary Parts of an Analytic Function Conjugate Harmonic Functions The Derivative of an Analytic Function Is Analytic Curves in the Complex Plane	1112 1113 1113 1114 1114
	82.9 82.10 82.11 82.12 82.13 82.14 82.15	The Cauchy-Riemann Equations and the Derivative The Cauchy-Riemann Equations in Polar Coordinates The Real and Imaginary Parts of an Analytic Function Conjugate Harmonic Functions The Derivative of an Analytic Function Is Analytic	1112 1113 1113 1114 1114 1116
	82.9 82.10 82.11 82.12 82.13 82.14 82.15 82.16	The Cauchy-Riemann Equations and the Derivative The Cauchy-Riemann Equations in Polar Coordinates The Real and Imaginary Parts of an Analytic Function Conjugate Harmonic Functions	1112 1113 1113 1114 1114 1116 1117
	82.9 82.10 82.11 82.12 82.13 82.14 82.15 82.16 82.17	The Cauchy-Riemann Equations and the Derivative The Cauchy-Riemann Equations in Polar Coordinates The Real and Imaginary Parts of an Analytic Function Conjugate Harmonic Functions	1112 1113 1113 1114 1114 1116 1117
	82.9 82.10 82.11 82.12 82.13 82.14 82.15 82.16 82.17 82.18	The Cauchy-Riemann Equations and the Derivative The Cauchy-Riemann Equations in Polar Coordinates The Real and Imaginary Parts of an Analytic Function Conjugate Harmonic Functions	1112 1113 1113 1114 1114 1116 1117 1117 1118
	82.9 82.10 82.11 82.12 82.13 82.14 82.15 82.16 82.16 82.17 82.18 82.19	The Cauchy-Riemann Equations and the Derivative The Cauchy-Riemann Equations in Polar Coordinates The Real and Imaginary Parts of an Analytic Function Conjugate Harmonic Functions	1112 1113 1113 1114 1114 1116 1117 1117 1118 1119

XLII Contents Volume 3

	82.21	Complex Integrals: General Case	1122
		Basic Properties of the Complex Integral	
		Taylor's Formula: First Shot	1123
	82.24	Cauchy's Theorem	1124
	82.25	Cauchy's Representation Formula	1125
	82.26	Taylor's Formula: Second Shot	1127
	82.27	Power Series Representation of Analytic Functions	1128
	82.28	Laurent Series	1130
	82.29	Residue Calculus: Simple Poles	1131
	82.30	Residue Calculus: Poles of Any Order	1133
		The Residue Theorem	
		Computation of $\int_0^{2\pi} R(\sin(t), \cos(t)) dt$	
	82.33	Computation of $\int_{-\infty}^{\infty} \frac{p(x)}{q(x)} dx$	1135
		Applications to Potential Theory in \mathbb{R}^2	
83	Fouri	er Series	1143
-		Introduction	
		Warm Up I: Orthonormal Basis in \mathbb{C}^n	
		Warm Up II: Series	
		Complex Fourier Series	
		Fourier Series as an Orthonormal Basis Expansion	
		Truncated Fourier Series and Best L_2 -Approximation.	
		Real Fourier Series	
	83.8	Basic Properties of Fourier Coefficients	1152
		The Inversion Formula	
	83.10	Parseval's and Plancherel's Formulas	1159
	83.11	Space Versus Frequency Analysis	1160
	83.12	Different Periods	1161
	83.13	Weierstrass Functions	116 1
	83.14	Solving the Heat Equation Using Fourier Series	1162
	83.15	Computing Fourier Coefficients with Quadrature	1164
	83.16	The Discrete Fourier Transform	1164
84	Fouri	er Transforms	1167
-	84.1	Basic Properties of the Fourier Transform	1169
		The Fourier Transform $\widehat{f}(\xi)$ Tends to 0 as $ \xi \to \infty$.	1171
		Convolution	1171
		The Inversion Formula	1171
	84.5	Parseval's Formula	1173
	84.6	Solving the Heat Equation Using the Fourier Transform	1173
	84.7	Fourier Series and Fourier Transforms	1174
	84.8	The Sampling Theorem	1175
	84.9	The Laplace Transform	1176
		Wavelets and the Haar Basis	1177

85	Analy	tic Functions Tool Bag	1181
	85.1	Differentiability and analyticity	1181
	85.2	The Cauchy-Riemann Equations	1181
	85.3	The Real and Imaginary Parts of an Analytic Function	1182
	85.4	Conjugate Harmonic Functions	1182
	85.5	Curves in the Complex Plane	1182
	85.6	An Analytic Function Defines a Conformal Mapping .	1183
	85.7	Complex Integrals	1183
	85.8	Cauchy's Theorem	1183
	85.9	Cauchy's Representation Formula	1183
	85.10	Taylor's Formula	1184
	85.11	The Residue Theorem	1184
86		er Analysis Tool Bag	1185
	86.1	Properties of Fourier Coefficients	1185
	86.2	Convolution	1185
	86.3	Fourier Series Representation	1186
	86.4	Parseval's Formula	1186
	86.5	Discrete Fourier Transforms	1186
	86.6	Fourier Transforms	1186
	86.7	Properties of Fourier Transforms	1187
	86.8	The Sampling Theorem	1187
87	Incon	npressible Navier-Stokes: Quick and Easy	1189
	87.1	Introduction	1189
	87.2	The Incompressible Navier-Stokes Equations	1190
	87.3	The Basic Energy Estimate for Navier-Stokes	1191
	87.4	Lions and his School	1192
	87.5	Turbulence: Lipschitz with Exponent 1/3?	1193
	87.6	Existence and Uniqueness of Solutions	1194
	87.7	Numerical Methods	1194
	87.8	The Stabilized $cG(1)dG(0)$ Method	1195
	87.9	The $cG(1)cG(1)$ Method	1196
	87.10	The $cG(1)dG(1)$ Method	1197
		Neumann Boundary Conditions	1197
		Computational Examples	1199
		ences	1205
			400=
	Index		-1207

Volume 1

$\begin{array}{c} \textbf{Derivatives} \\ \textbf{and} \\ \textbf{Geometry in } \mathbb{R}^3 \\ \end{array}$

$$|u(x_j) - u(x_{j-1})| \le L_u |x_j - x_{j-1}|$$

$$u(x_j) - u(x_{j-1}) \approx u'(x_{j-1})(x_j - x_{j-1})$$

$$a \cdot b = a_1 b_1 + a_2 b_2 + a_3 b_3$$

What is Mathematics?

The question of the ultimate foundations and the ultimate meaning of mathematics remains open; we do not know in what direction it will find its final solution or whether a final objective answer may be expected at all. "Mathematizing" may well be a creative activity of man, like language or music, of primary originality, whose historical decisions defy complete objective rationalization. (Weyl)

1.1 Introduction

We start out by giving a very brief idea of the nature of mathematics and the role of mathematics in our society.

1.2 The Modern World: Automatized Production and Computation

The mass consumption of the *industrial society* is made possible by the *automatized mass production* of material goods such as food, clothes, housing, TV-sets, CD-players and cars. If these items had to be produced by hand, they would be the privileges of only a select few.

Analogously, the emerging information society is based on mass consumption of automatized computation by computers that is creating a new "virtual reality" and is revolutionizing technology, communication, admin-

Fig. 1.1. First picture of book printing technique (from Danse Macabre, Lyon 1499)

istration, economy, medicine, and the entertainment industry. The information society offers immaterial goods in the form of knowledge, information, fiction, movies, music, games and means of communication. The modern PC or lap-top is a powerful computing device for mass production/consumption of information e.g. in the form of words, images, movies and music.

Key steps in the automatization or mechanization of production were: Gutenbergs's book printing technique (Germany, 1450), Christoffer Polhem's automatic machine for clock gears (Sweden, 1700), The Spinnning Jenny (England, 1764), Jacquard's punched card controlled weaving loom (France, 1801), Ford's production line (USA, 1913), see Fig. 1.1, Fig. 1.2, and Fig. 1.3.

Key steps in the automatization of computation were: Abacus (Ancient Greece, Roman Empire), Slide Rule (England, 1620), Pascals Mechanical Calculator (France, 1650), Babbage's Difference Machine (England, 1830), Scheutz' Difference Machine (Sweden, 1850), ENIAC Electronic Numerical Integrator and Computer (USA, 1945), and the Personal Computer PC (USA, 1980), see Fig. 1.5, Fig. 1.6, Fig. 1.7 and Fig. 1.8. The Difference Machines could solve simple differential equations and were used to compute tables of elementary functions such as the logarithm. ENIAC was one of the first modern computers (electronic and programmable), consisted of 18.000 vacuum tubes filling a room of 50 × 100 square feet with a weight of 30 tons and energy consuming of 200 kilowatts, and was used to solve the differential equations of ballistic firing tables as an important part of the Allied World War II effort. A modern laptop at a cost of \$2000 with a processor speed of 2 GHz and internal mem-

Fig. 1.2. Christoffer Polhem's machine for clock gears (1700), Spinning Jenny (1764) and Jaquard's programmable loom (1801)

Fig. 1.3. Ford assembly line (1913)

ory of 512 Mb has the computational power of hundreds of thousands of ENIACs.

Automatization (or automation) is based on frequent repetition of a certain algorithm or scheme with new data at each repetition. The algorithm may consist of a sequence of relatively simple steps together creating a more complicated process. In automatized manufacturing, as in the production line of a car factory, physical material is modified following a strict repetitive scheme, and in automatized computation, the 1s and 0s of the microprocessor are modified billions of times each second following the computer program. Similarly, a genetic code of an organism may be seen as an algorithm that generates a living organism when realized in interplay with the environment. Realizing a genetic code many times (with small variations) generates populations of organisms. Mass-production is the key to increased complexity following the patterns of nature: elementary particle \rightarrow atom \rightarrow molecule and molecule \rightarrow cell \rightarrow organism \rightarrow population, or the patterns of our society: individual \rightarrow group \rightarrow society or computer \rightarrow computer network \rightarrow global net.

1.3 The Role of Mathematics

Mathematics may be viewed as the language of computation and thus lies at the heart of the modern information society. Mathematics is also the language of science and thus lies at the heart of the industrial society that grew out of the scientific revolution in the 17th century that began when Leibniz and Newton created Calculus. Using Calculus, basic laws of mechanics and physics, such as Newton's law, could be formulated as mathematical mod-

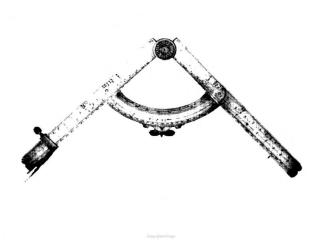
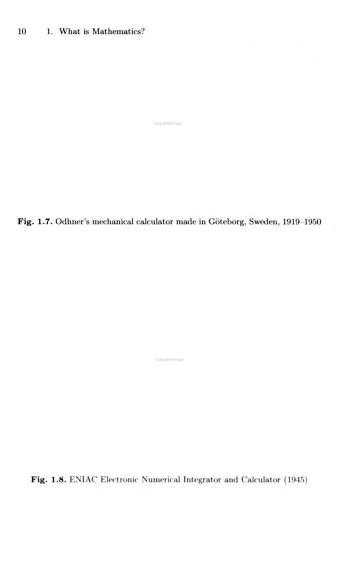


Fig. 1.5. Classical computational tools: Abacus (300 B.C.-), Galileo's Compass (1597) and Slide Rule (1620-)



1.4 Design and Production of Cars

In the car industry, a model of a component or complete car can be made using Computer Aided Design CAD. The CAD-model describes the geometry of the car through mathematical expressions and the model can be displayed on the computer screen. The performance of the component can then be tested in computer simulations, where differential equations are solved through massive computation, and the CAD-model is used as input of geometrical data. Further, the CAD data can be used in automatized production. The new technique is revolutionizing the whole industrial process from design to production.

1.5 Navigation: From Stars to GPS

A primary force behind the development of geometry and mathematics since the Babylonians has been the need to navigate using information from the positions of the planets, stars, the Moon and the Sun. With a clock and a sextant and mathematical tables, the sea-farer of the 18th century could determine his position more or less accurately. But the results depended strongly on the precision of clocks and observations and it was easy for large errors to creep in. Historically, navigation has not been an easy job.

During the last decade, the classical methods of navigation have been replaced by GPS, the Global Positioning System. With a GPS navigator in hand, which we can buy for a couple of hundred dollars, we get our coordinates (latitude and longitude) with a precision of 50 meters at the press of a button. GPS is based on a simple mathematical principle known already to the Greeks: if we know our distance to three point is space with known coordinates then we can compute our position. The GPS uses this principle by measuring its distance to three satellites with known positions, and then computes its own coordinates. To use this technique, we need to deploy satellites, keep track of them in space and time, and measure relevant distances, which became possible only in the last decades. Of course, computers are used to keep track of the satellites, and the microprocessor of a hand-held GPS measures distances and computes the current coordinates.

The GPS has opened the door to mass consumption in navigation, which was before the privilege of only a few.

1.6 Medical Tomography

The computer tomograph creates a pictures of the inside of a human body by solving a certain integral equation by massive computation, with data

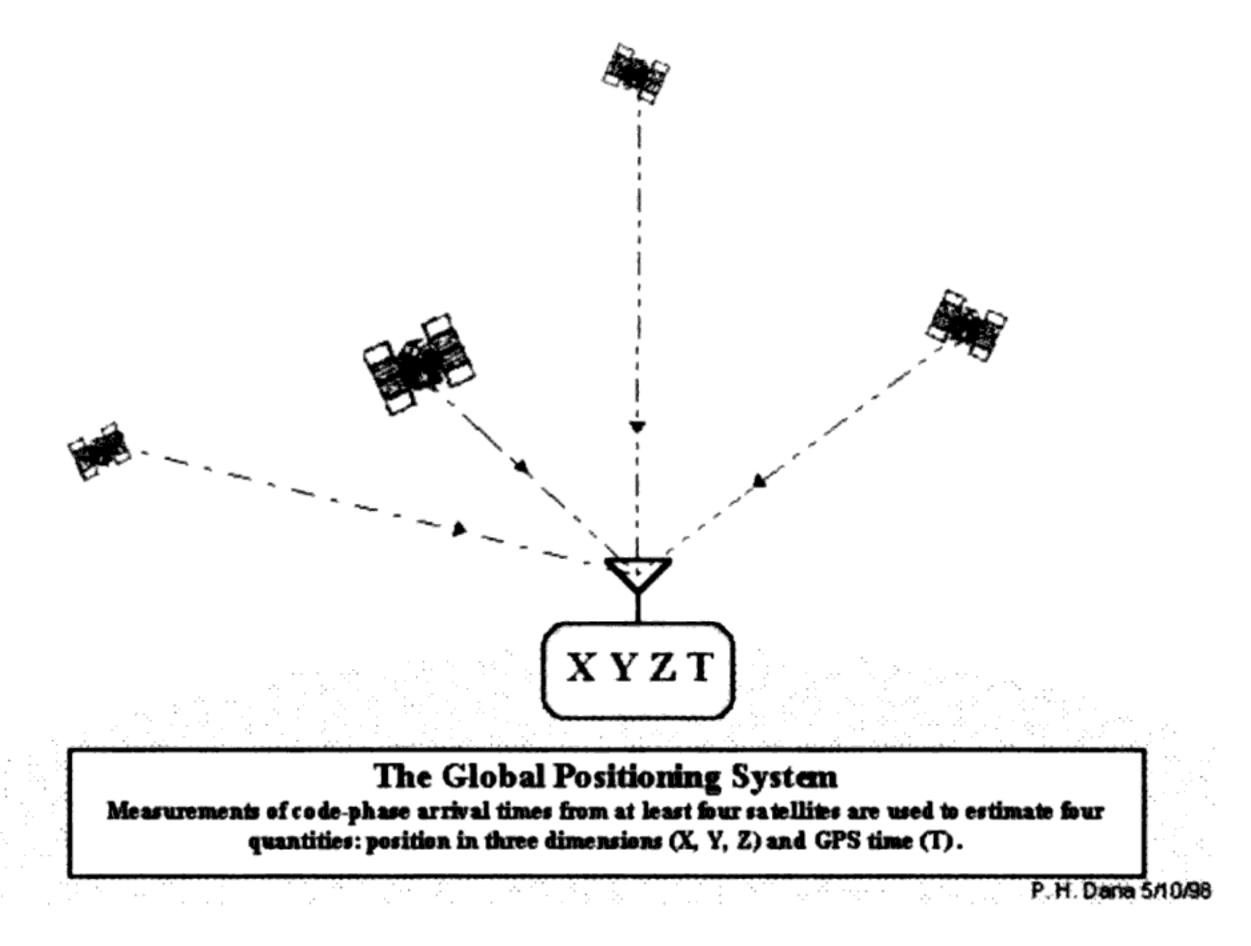


Fig. 1.9. GPS-system with 4 satellites

coming from measuring the attenuation of very weak X-rays sent through the body from different directions. This technique offers mass consumption of medical imaging, which is radically changing medical research and practice.

1.7 Molecular Dynamics and Medical Drug Design

The classic way in which new drugs are discovered is an expensive and time-consuming process. First, a physical search is conducted for new organic chemical compounds, for example among the rain forests in South America. Once a new organic molecule is discovered, drug and chemical companies license the molecule for use in a broad laboratory investigation to see if the compound is useful. This search is conducted by expert organic chemists who build up a vast experience with how compounds can interact and which kind of interactions are likely to prove useful for the purpose of controlling a disease or fixing a physical condition. Such experience is needed to reduce the number of laboratory trials that are conducted, otherwise the vast range of possibilities is overwhelming.

The use of computers in the search for new drugs is rapidly increasing. One use is to makeup new compounds so as to reduce the need to make expensive searches in exotic locations like southern rain forests. As part of this search, the computer can also help classify possible configurations of

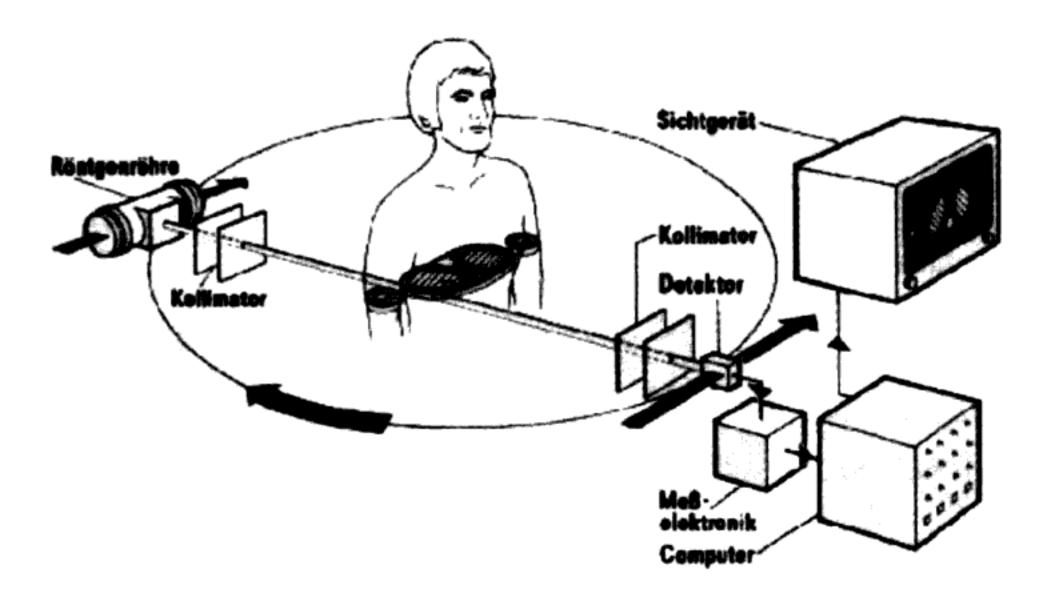


Fig. 1.10. Medical tomograph

molecules and provide likely ranges of interactions, thus greatly reducing the amount of laboratory testing time that is needed.

1.8 Weather Prediction and Global Warming

Weather predictions are based on solving differential equations that describe the evolution of the atmosphere using a super computer. Reasonably reliable predictions of daily weather are routinely done for periods of a few days. For longer periods, the reliability of the simulation decreases rapidly, and with present day computers daily weather predictions for a period of two weeks are impossible.

However, forecasts over months of averages of temperature and rainfall are possible with present day computer power and are routinely performed.

Long-time simulations over periods of 20–50 years of yearly temperature-averages are done today to predict a possible *global warming* due to the use of fossil energy. The reliability of these simulations are debated.

1.9 Economy: Stocks and Options

The Black-Scholes model for pricing options has created a new market of so called derivative trading as a complement to the stock market. To correctly price options is a mathematically complicated and computationally intensive task, and a stock broker with first class software for this purpose (which responds in a few seconds), has a clear trading advantage. The ants in a group of ants or bees in a bees hive also have a language for communication. In fact in modern biology, the interaction between cells or proteins in a cell is often described in terms of entities "talking to each other".

It appears that we as human beings use our language when we think. We then seem to use the language as a model in our head, where we try various possibilities in *simulations* of the real world: "If that happens, then I'll do this, and if instead that happens, then I will do so and so...". Planning our day and setting up our calender is also some type of modeling or simulation of events to come. Simulations by using our language thus seems to go on in our heads all the time.

There are also other languages like the language of musical notation with its notes, bars, scores, et cetera. A musical score is like a model of the real music. For a trained composer, the model of the written score can be very close to the real music. For amateurs, the musical score may say very little, because the score is like a foreign language which is not understood.

1.11 Mathematics as the Language of Science

Mathematics has been described as the language of science and technology including mechanics, astronomy, physics, chemistry, and topics like fluid and solid mechanics, electromagnetics et cetera. The language of mathematics is used to deal with geometrical concepts like position and form and mechanical concepts like velocity, force and field. More generally, mathematics serves as a language in any area that includes quantitative aspects described in terms of numbers, such as economy, accounting, statistics et cetera. Mathematics serves as the basis for the modern means of electronic communication where information is coded as sequences of 0's and 1's and is transferred, manipulated or stored.

The words of the language of mathematics often are taken from our usual language, like points, lines, circles, velocity, functions, relations, transformations, sequences, equality, inequality et cetera.

A mathematical word, term or concept is supposed to have a specific meaning defined using other words and concepts that are already defined. This is the same principle as is used in a Thesaurus, where relatively complicated words are described in terms of simpler words. To start the definition process, certain fundamental concepts or words are used, which cannot be defined in terms of already defined concepts. Basic relations between the fundamental concepts may be described in certain axioms. Fundamental concepts of Euclidean geometry are point and line, and a basic Euclidean axiom states that through each pair of distinct points there is a unique line passing. A theorem is a statement derived from the axioms or other

1.13 What Is Science?

The theoretical kernel of $natural\ science\ may$ be viewed as having two components

- formulating equations (modeling),
- solving equations (computation).

Together, these form the essence of mathematical modeling and computational mathematical modeling. The first really great triumph of science and mathematical modeling is Newton's model of our planetary system as a set of differential equations expressing Newton's law connecting force, through the inverse square law, and acceleration. An algorithm may be seen as a strategy or constructive method to solve a given equation via computation. By applying the algorithm and computing, it is possible to simulate real phenomena and make predictions.

Traditional techniques of computing were based on symbolic or numerical computation with pen and paper, tables, slide ruler and mechanical calculator. Automatized computation with computers is now opening new possibilities of simulation of real phenomena according to Natures own principle of massive repetition of simple operations, and the areas of applications are quickly growing in science, technology, medicine and economics.

Mathematics is basic for both steps (i) formulating and (ii) solving equation. Mathematics is used as a language to formulate equations and as a set of tools to solve equations.

Fame in science can be reached by formulating or solving equations. The success is usually manifested by connecting the name of the inventor to the equation or solution method. Examples are legio: Newton's method, Euler's equations, Lagrange's equations, Poisson's equation, Laplace's equation, Navier's equation, Navier-Stokes' equations, Boussinesq's equation, Einstein's equation, Schrödinger's equation, Black-Scholes formula..., most of which we will meet below.

1.14 What Is Conscience?

The activity of the brain is believed to consist of electrical/chemical signals/waves connecting billions of synapses in some kind of large scale computation. The question of the nature of the *conscience* of human beings has played a central role in the development of human culture since the early Greek civilization, and today computer scientists seek to capture its evasive nature in various forms of Artificial Intelligence AI. The idea of a division of the activity of the brain into a (small) *conscious* "rational" part and a (large) *unconscious* "irrational" part, is widely accepted since the days of Freud. The rational part has the role of "analysis" and "control" towards

some "purpose" and thus has features of Soul, while the bulk of the "computation" is Body in the sense that it is "just" electrical/chemical waves. We meet the same aspects in numerical optimization, with the optimization algorithm itself playing the role of Soul directing the computational effort towards the goal, and the underlying computation is Body.

We have been brought up with the idea that the conscious is in control of the mental "computation", but we know that this is often not the case. In fact, we seem to have developed strong skills in various kinds of after-rationalization: whatever happens, unless it is an "accident" or something "unexpected", we see it as resulting from a rational plan of ours made up in advance, thus turning a posteriori observations into a priori predictions.

1.15 How to Come to Grips with the Difficulties of Understanding the Material of this Book and Eventually Viewing it as a Good Friend

We conclude this introductory chapter with some suggestions intended to help the reader through the most demanding first reading of the book and reach a state of mind viewing the book as a good helpful friend, rather than the opposite. From our experience of teaching the material of this book, we know that it may evoke quite a bit of frustration and negative feelings, which is not very productive.

Mathematics Is Difficult: Choose Your Own Level of Ambition

First, we have to admit that mathematics is a difficult subject, and we see no way around this fact. Secondly, one should realize that it is perfectly possible to live a happy life with a career in both academics and industry with only elementary knowledge of mathematics. There are many examples including Nobel Prize Winners. This means that it is advisable to set a level of ambition in mathematics studies which is realistic and fits the interest profile of the individual student. Many students of engineering have other prime interests than mathematics, but there are also students who really like mathematics and theoretical engineering subjects using mathematics. The span of mathematical interest thus may be expected to be quite wide in a group of students following a course based on this book, and it seems reasonable that this would be reflected in the choice of level of ambition.

Advanced Material: Keep an Open Mind and Be Confident

The book contains quite a bit of material which is "advanced" and not usually met in undergraduate mathematics, and which one may bypass and still be completely happy. It is probably better to be really familiar with

and understand a smaller set of mathematical tools and have the ability to meet new challenges with some self-confidence, than repeatedly failing to digest too large portions. Mathematics is so rich, that even a life of fullytime study can only cover a very small part. The most important ability must be to meet new material with an open mind and some confidence!

Some Parts of Mathematics Are Easy

On the other hand, there are many aspects of mathematics which are not so difficult, or even "simple", once they have been properly understood. Thus, the book contains both difficult and simple material, and the first impression from the student may give overwhelming weight to the former. To help out we have collected the most essential nontrivial facts in short summaries in the form of Calculus Tool Bag I and II, Linear Algebra Tool Bag, Differential Equations Tool Bag, Applications Tool Bag, Fourier Analysis Tool Bag and Analytic Functions Tool Bag. The reader will find the tool bags surprisingly short: just a couple pages, altogether say 15–20 pages. If properly understood, this material carries a long way and is "all" one needs to remember from the math studies for further studies and professional activities in other areas. Since the book contains about 1200 pages it means 50–100 pages of book text for each one page of summary. This means that the book gives more than the absolute minimum of information and has the ambition to give the mathematical concepts a perspective concerning both history and applicability today. So we hope the student does not get turned off by the quite a massive number of words, by remembering that after all 15–20 pages captures the essential facts. During a period of study of say one year and a half of math studies, this effectively means about one third of a page each week!

Increased/Decreased Importance of Mathematics

The book reflects both the increased importance of mathematics in the information society of today, and the decreased importance of much of the analytical mathematics filling the traditional curriculum. The student thus should be happy to know that many of the traditional formulas are no longer such a must, and that a proper understanding of relatively few basic mathematical facts can help a lot in coping with modern life and science.

Which Chapters Can I Skip in a First Reading?

We indicate by * certain chapters directed to applications, which one may by-pass in a first reading without loosing the main thread of the presentation, and return to at a later stage if desired.

Chapter 1 Problems

- ${\bf 1.1.}\,$ Find out which Nobel Prize Winners got the prize for formulating or solving equations.
- 1.2. Reflect about the nature of "thinking" and "computing".
- 1.3. Find out more about the topics mentioned in the text.
- 1.4. (a) Do you like mathematics or hate mathematics, or something in between? Explain your standpoint. (b) Specify what you would like to get out of your studies of mathematics.
- 1.5. Present some basic aspects of science.

Fig. 1.12. Left person: "Isn't it remarkable that one can compute the distance to stars like Cassiopeja, Aldebaran and Sirius?". Right person: "I find it even more remarkable that one may know their names!" (Assar by Ulf Lundquist)

2.2 Math Experience

22

Math Experience is a collection of Matlab GUI software designed to offer a deeper understanding of important mathematical concepts and ideas such as, for example, convergence, continuity, linearization, differentiation, Taylor polynomials, integration, etc. The idea is to provide on-screen computer "labs" in which the student, by himself guided by a number of well designed questions, can seek to fully understand (a) the concepts and ideas as such and (b) the mathematical formulas and equations describing the concepts, by interacting with the lab environment in different ways. For example, in the Taylor lab (see Fig. 2.1) it is possible to give a function, or pick one from a gallery, and study its Taylor polynomial approximation of different degrees, how it depends on the point of focus by mouse-dragging the point, how it depends on the distance to the point by zooming in and out etc. There is also a movie where the terms in the Taylor polynomial are added one at a time. In the MultiD Calculus lab (see Fig. 2.2) it is possible to define a function $u(x_1, x_2)$ and compute its integral over a given curve or a given domain, to view its gradient field, contour plots, tangent planes etc. One may also study vector fields (u, v), view their divergence and rotation, compute the integrals of these quantities to verify the fundamental theorems of vector calculus, view the (u, v) mapped domain and the Jacobian of the map etc, etc.

The following labs are available from the book web page:

- Func lab about relations and functions, inverse function etc.
- Graph Gallery elementary functions and their parameter dependence.
- Cauchy lab about sequences & convergence
- Lipschitz lab the concept of continuity
- Root lab about bisection and fixed point iteration
- Linearization and the derivative
- Newtons lab illustrating Newton's method
- Taylor lab polynomials
- Opti lab elementary optimization
- Piecewise polynomial lab about piecewise polynomial approximation
- Integration lab Euler and Riemann summation, adaptive integration

Copyrighted image

Fig. 2.2. The MultiD Calculus lab

Introduction to Modeling

The best material model of a cat is another, or preferably the same, cat. (Rosenblueth/Wiener in Philosophy of Science 1945)

3.1 Introduction

We start by giving two basic examples of the use of mathematics for describing practical situations. The first example is a problem in household economy and the second is a problem in surveying, both of which have been important fields of application for mathematics since the time of the Babylonians. The models are very simple but illustrate fundamental ideas.

3.2 The Dinner Soup Model

You want to make a soup for dinner together with your roommate, and following a recipe you ask your roommate to go to the grocery store and buy 10 dollars worth of potatoes, carrots, and beef according to the proportions 3:2:1 by weight. In other words, your roommate has 10 dollars to spend on the ingredients, which should be bought in the amounts so that by weight there are three times as much potatoes as beef and two times as much carrots as beef. At the grocery store, your roommate finds that potatoes are 1 dollar per pound, carrots are 2 dollars per pound, and beef is 8 dollars per pound. Your roommate thus faces the problem of figuring out how much of each ingredient to buy to use up the 10 dollars.

One way to solve the problem is by trial and error as follows: Your roommate could take quantities of the ingredients to the cash register in the proportions of 3:2:1 and let the clerk check the price, repeating until a total of 10 dollars is reached. Of course, both your roommate and the clerk could probably think of better ways to spend the afternoon. Another possibility would be to make a *mathematical model* of the situation and then seek to find the correct amounts to buy by doing some computations. The basic idea would be to use brains and pen and paper or a calculator, instead of labor intensive brute physical work.

The mathematical model may be set up as follows: Recalling that we want to determine the amounts of ingredients to buy, we notice that it is enough to determine the amount of beef, since we'll buy twice as much carrots as beef and three times as much potatoes as beef. Let's give a name to the quantity to determine. Let x denote the amount of meat in pounds to buy. The $symbol\ x$ here represents an unknown quantity, or unknown, that we are seeking to determine by using available information.

If the amount of meat is x pounds, then the price of the meat to buy is 8x dollars by the simple computation

cost of meat in dollars =
$$x$$
 pounds $\times 8 \frac{\text{dollars}}{\text{pound}} = 8x$ dollars.

Since there should be three times as much potatoes as meat by weight, the amount of potatoes in pounds is 3x and the cost of the potatoes is 3x dollars since the price of potatoes is one dollar per pound. Finally, the amount of carrots to buy is 2x and the cost is 2 times 2x = 4x dollars, since the price is 2 dollars per pound. The total cost of meat, potatoes and carrots is found by summing up the cost of each

$$8x + 3x + 4x = 15x$$
.

Since we assume that we have 10 dollars to spend, we get the relation

$$15x = 10, (3.1)$$

which expresses the equality of total cost and available money. This is an equation involving the unknown x and data determined by the physical situation. From this equation, your roommate can figure out how much beef to buy. This is done by dividing both sides of (3.1) by 15, which gives $x = 10/15 = 2/3 \approx 0.67$ pounds of meat. The amount of carrots should then be $2 \times 2/3 = 4/3 \approx 1.33$, and finally the amount of potatoes $3 \times 2/3 = 2$ pounds.

The mathematical model for this situation is 15x = 10, where x is the amount of meat, 15x is the total cost and 10 is the available money. The modeling consists in expressing the total cost of the ingredients 15x in terms of the amount of beef x. Note that in this model, we only take into account

what is essential for the current purpose of buying potatoes, carrots and meat for the Dinner Soup, and we did not bother to write down the prices of other items, like ice cream or beer. Determining the useful information is an important, and sometimes difficult, part of the mathematical modeling.

A nice feature of mathematical models is that they can be reused to simulate different situations. For example, if you have 15 dollars to spend, then the model 15x = 15 arises with solution x = 1. If you have 25 dollars to spend, then the model is 15x = 25 with solution x = 25/15 = 5/3. In general, if the amount of money y is given, then the model is 15x = y. In this model we use the two symbols x and y, and assume that the amount of money y is given and the amount of beef x is an unknown quantity to be determined from the equation (15x = y) of the model. The roles could shift around: you may think of the amount of beef x as being given and the total cost or expenditure y to be determined (according to the formula y = 15x). In the first case, we would think of the amount of beef x as a function of the expenditure y and in the second the expenditure y as a function of x.

Assigning symbols to relevant quantities, known or unknown, is an important step in setting up a mathematical model of something. The idea of assigning symbols for unknown quantities was used already by the Babylonians (who had frequent use of models like the Dinner Soup model in organizing the feeding of the many people working on their irrigation systems).

Suppose that we could not solve the equation 15x = 10, because of a lack of skill in solving equations (we may have forgotten the trick of dividing by 15 that we learned in school). We could then try to get a solution by some kind of trial and error strategy as follows. First we assume that x = 1. We then find that the total cost is 15 dollars, which is too much. We then try with a smaller quantity of meat, say x = 0.6, and compute the total cost to 9 dollars, which is too little. We then try with something between 0.6 and 1, say x = 0.7 and find that the cost would be 10.5 dollars, which is a little too much. We conclude that the right amount must be somewhere between 0.6 and 0.7, probably closer 0.7. We can continue in the same way to find as many decimals of x as we like. For instance we check next in the same way that x must be some where between 0.66 and 0.67. In this case we know the exact answer $x = \frac{2}{3} = 0.66666...$ The trial and error strategy just described is a model of the process of bringing food to the counter and letting the cashier compute the total prize. In the model we compute the prize ourselves without having to physically collect the items and bring them to the counter, which simplifies the trial and error process.

 $\sqrt{2}$, whatever it is, is between 1 and 2. Next we can check $1.1^2=1.21$, $1.2^2=1.44$, $1.3^2=1.69$, $1.4^2=1.96$, $1.5^2=2.25$, $1.6^2=2.56$, $1.7^2=2.89$, $1.8^2=3.24$, $1.9^2=3.61$. Apparently $\sqrt{2}$ is between 1.4 and 1.5. Next we can try to fix the third decimal. Now we find that $1.41^2=1.9881$ while $1.42^2=2.0164$. So apparently $\sqrt{2}$ is between 1.41 and 1.42 and likely closer to 1.41. It appears that proceeding in this way, we can determine as many decimal places of $\sqrt{2}$ as we like, and we may consider the problem of computing how much drain pipe to buy to be solved!

Below we will meet many equations that have to be solved by using some variation of a trial and error strategy. In fact, most mathematical equations cannot be solved exactly by some algebraic manipulations, as we could do (if we were sufficiently clever) in the case of the Dinner Soup model (3.1). Consequently, the trial and error approach to solving mathematical equations is fundamentally important in mathematics. We shall also see that trying to solve equations such as $x^2 = 2$ carries us directly into the very heart of mathematics, from Pythagoras and Euclid through the quarrels on the foundations of mathematics that peaked in the 1930s and on into the present day of the modern computer.

3.4 A System of Equations: The Dinner Soup/Ice Cream Model

Suppose you would like to finish off the Dinner Soup with some ice cream dessert at the cost of 3 dollars a pound, still at the total expense of 10 dollars. How much of each item should now be bought?

Well, if the amount ice cream is y pounds, the total cost will be 15x + 3y and thus we have the equation 15x + 3y = 10 expressing that the total cost is equal to the available money. We now have two unknowns x and y, and we need one more equation. So far, we would be able to set x = 0 and solve for $y = \frac{10}{3}$ spending all the money on ice cream. This would go against some principle we learned as small kids. The second equation needed could come from some idea of balancing the amount of ice cream (junk food) to the amount of carrots (healthy food), for example according to the formula 2x = y + 1, or 2x - y = 1. Altogether, we would thus get the following system of two equations in the two unknowns x and y:

$$15x + 3y = 10,$$
$$2x - y = 1.$$

Solving for y in the second equation, we get y = 2x - 1, which inserted into the first equation gives

$$15x + 6x - 3 = 10$$
, that is $21x = 13$, that is, $x = \frac{13}{21}$.

Chapter 3 Problems

- **3.1.** Suppose that the grocery store sells potatoes for 40 cents per pound, carrots for 80 cents per pound, and beef for 40 cents per *ounce*. Determine the model relation for the total price.
- **3.2.** Suppose that you change the soup recipe to have equal amounts of carrots and potatoes while the weight of these combined should be six times the weight of beef. Determine the model relation for the total price.
- **3.3.** Suppose you go all out and add onions to the soup recipe in the proportion of 2:1 to the amount of beef, while keeping the proportions of the other ingredients the same. The price of onions in the store is \$1 per pound. Determine the model relation for the total price.
- **3.4.** While flying directly over the airport in a holding pattern at an altitude of 1 mile, you see your high rise condominium from the window. Knowing that the airport is 4 miles from your condominium and pretending that the condominium has height 0, how far are you from home and a cold beer?
- 3.5. Devise a model of the draining of a yard that has three sides of approximately the same length 2 assuming that we drain the yard by laying a pipe from one corner to the midpoint of the opposite side. What quantity of pipe do we need?
- **3.6.** A father and his child are playing with a teeter-totter which has a seatboard 12 feet long. If the father weighs 170 pounds and the child weighs 45 pounds, construct a model for the location of the pivot point on the board in order for the teeter-totter to be in perfect balance? Hint: recall the principle of the lever which says that the products of the distances from the fulcrum to the masses on each end of a lever must be equal for the lever to be in equilibrium.

A Very Short Calculus Course

Mathematics has the completely false reputation of yielding infallible conclusions. Its infallibility is nothing but identity. Two times two is not four, but it is just two times two, and that is what we call four for short. But four is nothing new at all. And thus it goes on in its conclusions, except that in the height the identity fades out of sight. (Goethe)

4.1 Introduction

Following up on the general idea of science as a combination of formulating and solving equations, we describe the bare elements of this picture from a mathematical point of view. We want to give a brief glimpse of the main themes of Calculus that will be discovered as we work through the volumes of this book. In particular, we will encounter the magical words of function, derivative, and integral. If you have some idea of these concepts already, you will understand some of the outline. If you have no prior acquaintance with these concepts, you can use this section to just get a first taste of what Calculus is all about without expecting to understand the details at this point. Keep in mind that this is just a glimpse of the actors behind the curtain before the play begins!

We hope the reader can use this chapter to get a grip on the essence of Calculus by reading just a couple of pages. But this is really impossible in some sense because calculus contains so many formulas and details that it is easy to get overwhelmed and discouraged. Thus, we urge the reader to browse through the following couple of pages to get a quick idea and then return later and confirm with an "of course".

On the other hand, the reader may be surprised that something that is seemingly explained so easily in a couple of pages, actually takes several hundred pages to unwind in this book (and other books). We don't seem to be able give a good explanation of this "contradiction" indicating that "what looks difficult may be easy" and vice versa. We also present short summaries of Calculus in Chapter Calculus Tool Bag I and Calculus Tool Bag II, which support the idea that a distilled essence of Calculus indeed can be given in a couple of pages.

4.2 Algebraic Equations

We will consider algebraic equations of the form: find \bar{x} such that

$$f(\bar{x}) = 0, \tag{4.1}$$

where f(x) is a function of x. Recall that f(x) is said to be a function of x if for each number x there is a number y = f(x) assigned. Often, f(x) is given by some algebraic formula: for example f(x) = 15x - 10 as in the Dinner Soup model, or $f(x) = x^2 - 2$ as in the Muddy Yard model.

We call \bar{x} a root of the equation f(x) = 0 if $f(\bar{x}) = 0$. The root of the equation 15x - 10 = 0 is $\bar{x} = \frac{2}{3}$. The positive root \bar{x} of the equation $x^2 - 2 = 0$ is equal to $\sqrt{2} \approx 1.41$. We will consider different methods to compute a root \bar{x} satisfying $f(\bar{x}) = 0$, including the trial and error method briefly presented above in the context of the Muddy Yard Model.

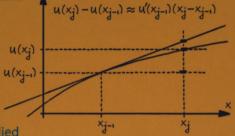
We will also meet systems of algebraic equations, where we seek to determine several unknowns satisfying several equations, as for the Dinner Soup/Ice cream model above.

4.3 Differential Equations

We will also consider the following differential equation: find a function x(t) such that for all t

$$x'(t) = f(t), \tag{4.2}$$

where f(t) is a given function, and x'(t) is the *derivative* of the function x(t). This equation has several new ingredients. First, we seek here a function x(t) with a set of different values x(t) for different values of the variable t, and not just one single value of x like the root the algebraic equation $x^2 = 2$ considered above. In fact, we met this already in the Dinner Soup problem in case of a variable amount of money y to spend, leading to the equation 15x = y with solution $x = \frac{y}{15}$ depending on the variable y, that is,



Applied Mathematics: Body

and Soul is a mathematics education reform project developed at Chalmers
University of Technology and includes a series of volumes and software.
The program is motivated by the computer revolution opening new possibilitites of computational mathematical modeling in mathematics, science and engineering. It consists of a synthesis of Mathematical Analysis (Soul), Numerical Computation (Body) and Application. Volumes I-III present a modern version of Calculus and Linear Algebra, including constructive/numerical techniques and applications intended for undergraduate programs in engineering and science. Further volumes present topics such as Dynamical Systems, Fluid Dynamics, Solid Mechanics and Electro-Magnetics on an advanced undergraduate/ graduate level.

This volume presents basics of Calculus starting with the construction of the natural, rational, real and complex numbers, and proceeding to analytic geometry in two and three space dimensions, Lipschitz continuous functions and derivatives, together with a variety of applications.

The authors are leading researchers in Computational Mathematics who have written various successful books.

Further information can be found at http://www.phi.chalmers.se/bodysoul/

