

# 20. Vorlesung

5.7.2021

**Basis:** **System:**  $\varphi_1, \dots, \varphi_n$  Lösung von  $\dot{x} = Ax$ ,

d.h. Sei  $t = 0$ :

$$\dot{\varphi}(t) = \alpha_1 \varphi_1(t) + \dots + \alpha_n \varphi_n(t)$$

$$\varphi(0) = 0,$$

Lösung von  $\dot{x} = Ax$ ,

$$\varphi(0) = 0,$$

$$\varphi : \varphi(t) \geq 0$$

$$, t \in \mathbb{D} \quad \mathbb{D}$$

**Frage:** Die Giv  $\varphi$  in  $x = Ax$   
 ist eindeutig durch  $A \omega$   $\varphi(\omega)$ .

**Ans:**

$$\varphi(\omega) = \alpha_1 \varphi_1(\omega) + \dots + \alpha_n \varphi_n(\omega)$$

**Frage:**

$$\varphi(\omega) = \alpha_1 \varphi_1(\omega) + \dots + \alpha_n \varphi_n(\omega)$$

**Ans:**

$$\varphi(\omega) \text{ Giv}$$

$$\varphi(\omega) = \varphi(\omega)$$

$\Rightarrow$

$$\varphi(\omega) = \varphi(\omega) =$$

$\square$

$$\det(A^T B) = \det(BA)$$

$$\operatorname{sp}(A^T B) = \operatorname{sp}(BA).$$

Sei  $B, C$  zwei  $n \times n$ -Matr. in  $\mathbb{R}$ .

**Ann:**

$$C = T^{-1} B T$$

**Frage:**

$$\operatorname{sp}(C) = \operatorname{sp}(T^{-1} B T)$$

$$= \operatorname{sp}(B T T^{-1}) = \operatorname{sp}(B).$$

Weyl :

$$e^{\tau A} = H + \tau A + \frac{1}{2!} \tau^2 A^2 + \dots$$

$$= H + \tau \left( A + \frac{1}{2!} \tau A^2 + \dots \right)$$

$$= H + \tau A e^{\tau A}$$

$$A e^{\tau A} = \sum_{i=1}^n \frac{\tau^i}{i!} A^i, \quad A e^{\tau A} = A.$$

$$e^{\tau A} = \left[ H_1 + \tau A_1 e^{\tau A_1}, \dots, H_n + \tau A_n e^{\tau A_n} \right].$$

$\rightarrow$

$$\det e^{\tau A}$$

$$= \det \left[ H_1 + \tau A_1 e^{\tau A_1}, \dots, H_n + \tau A_n e^{\tau A_n} \right].$$

$$= \det (H_1, \dots, H_n)$$

$$+ \tau \sum_{i=1}^n \det (H_1, \dots, A_i e^{\tau A_i}, \dots, H_n)$$

$$+ O(\tau^2)$$

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Ans:  $\det A = 1 + \sum_{i=1}^n a_{ii} + O(t^2)$

$\Rightarrow 1 + t \cdot \sum_{i=1}^n a_{ii} + O(t^2)$

$\Rightarrow 1 + t \cdot \text{tr}(A) + O(t^2)$

Ans:

$\frac{d}{dt} \det A = \text{tr}(A)$

$\Rightarrow \text{tr}(A)$

Def:

$$d(f) := \det \rho_f :$$

$$\begin{aligned} d(\sigma + \tau) &= \det \rho_{(\sigma + \tau)} \\ &= \det \rho_{\sigma + \tau} \\ &= \det \rho_{\sigma} \rho_{\tau} \\ &= \det(\rho_{\sigma}) \cdot \det(\rho_{\tau}) \\ &= d(\sigma) \cdot d(\tau) \end{aligned}$$

↳ Parav.  
Gruppe.

$$\begin{aligned} \frac{d}{d\sigma} \rho_f &= \frac{d}{d\sigma} d(\sigma + \tau) \Big|_{\sigma=0} \\ &= \frac{d}{d\sigma} d(\sigma) d(\tau) \Big|_{\sigma=0} \\ &= \frac{d}{d\sigma} d(\sigma) \Big|_{\sigma=0} d(\tau) \\ &= \text{ker} \rho_f \cdot d(\tau) \end{aligned}$$

$\mathbb{R}^n$ :

$$\det(A) = \det(A^T)$$

$$\det(A) = \det(A^{-1})^{-1} = 1$$

$\mathbb{R}^n$ :

$$\det(A) = \det(A^{-1})^{-1} \quad \square$$

$\mathbb{R}^n$  Zeit  $t$ , Abb zu  $x = Ax$

$$\mathbb{R}^n : x \mapsto \mathbb{R}^n x$$

$\det \mathbb{R}^n$  Zusammenhang:

$$\Delta : U \rightarrow U$$

$$K \subset U$$

$$\det(\Delta|_K) = \det(\Delta) \cdot \det(K)$$

$$(Tg)' = Tg' = \underline{T Bg}$$

$$(Tg)' = x' = Ax = \underline{ATg}$$

$A \in \mathbb{R}^{n \times n}$ :

$$T Bg = ATg, \quad g \in \mathbb{R}^n$$

$\mathbb{R}^n$

$$TB = AT$$

$$B = T^{-1}AT$$

$\mathbb{C}^n$  real casaire

$\mathbb{C}^n$  real  $\rightarrow$   $\mathbb{R}^{2n}$

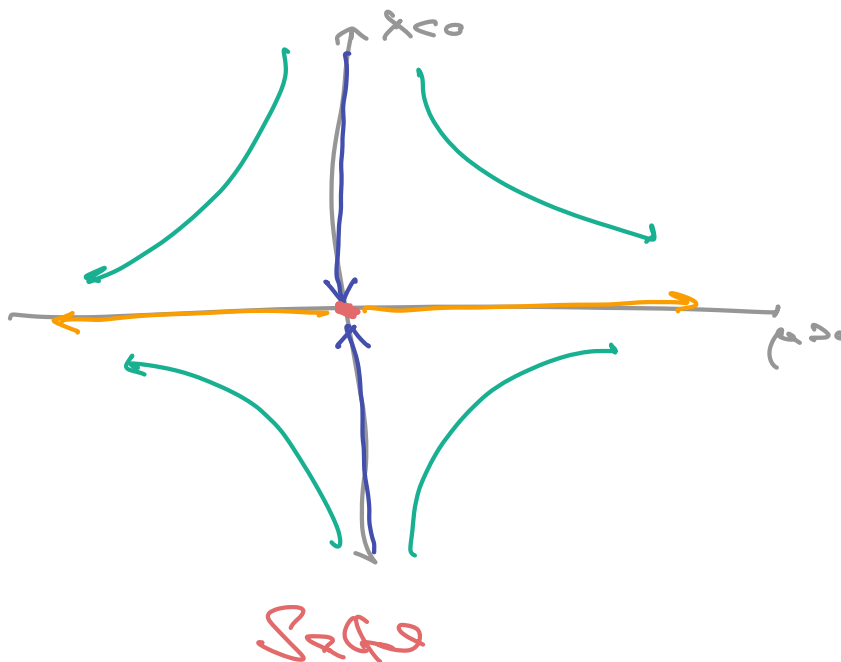
$\mathbb{C}^n$  complex  $\rightarrow$   $\mathbb{C}^n$

} diagonal  
Jordan

$$\varphi \in \mathbb{C}^n \equiv 0$$

$$\begin{aligned}
 \dot{x} &= Ax \\
 &= \begin{pmatrix} a_{11} & a_{12} \\ a_{21} & a_{22} \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \end{pmatrix} \\
 &= \begin{pmatrix} a_{11}x_1 + a_{12}x_2 \\ a_{21}x_1 + a_{22}x_2 \end{pmatrix}, \quad a_i, b_i \in \mathbb{R}
 \end{aligned}$$

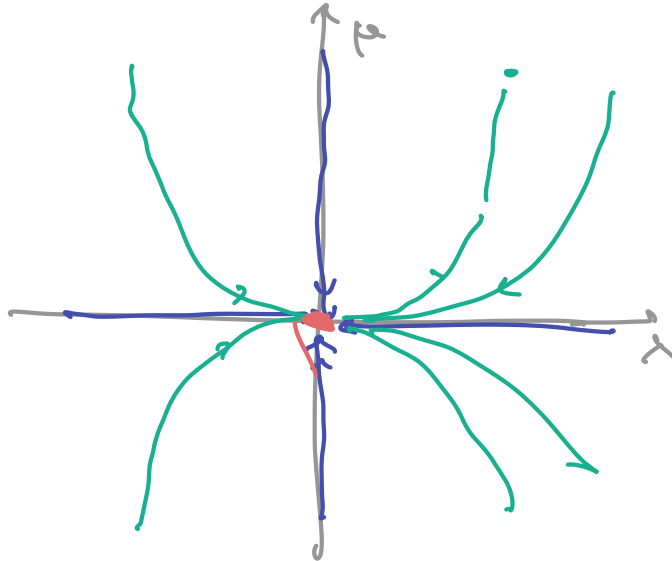
$\lambda_1 < 0$  :  $\lambda_2$  verschwindet





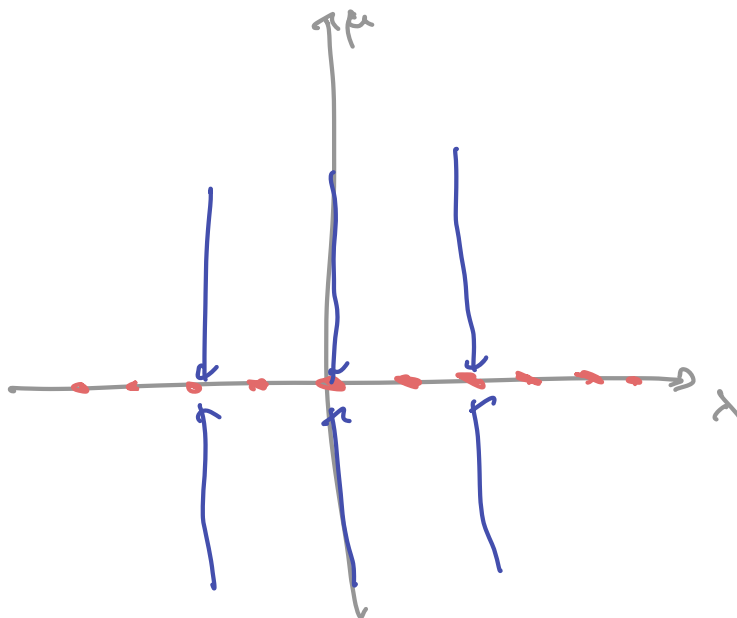
$$\mu < \lambda < 0$$

stabile Knoten



$$\mu < 0 < \lambda$$

sattelpunkt



Bew.:

$$T^T A T = \text{diag}(\lambda_1, \dots, \lambda_n)$$

$$= \lambda \cdot I$$

für alle

$$\Rightarrow A = T^{-1} (\lambda T T^T) T$$

$$= \lambda T T^T$$

$$= \lambda I$$

(ii)  $A$  diagonal  $\lambda$

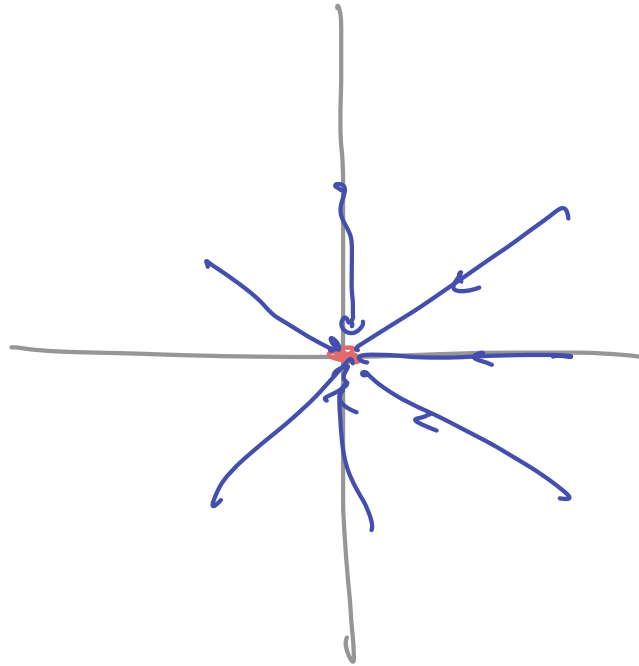
$$A = \lambda I$$

für alle  $\lambda$

$$\rho(A) = \lambda$$

Case

$\lambda = 0$  :



A Jordan form:

$$A = \begin{pmatrix} \lambda & 1 \\ & \lambda \end{pmatrix}$$

$$= \lambda \cdot I + N, \quad N = \begin{pmatrix} 0 & 1 \\ 0 & 0 \end{pmatrix}$$

Ans:

$$N^2 = 0$$

$$P^{-1}AP = P^{-1}(\lambda I + N)P$$

$$= P^{-1}\lambda I P + P^{-1}NP$$

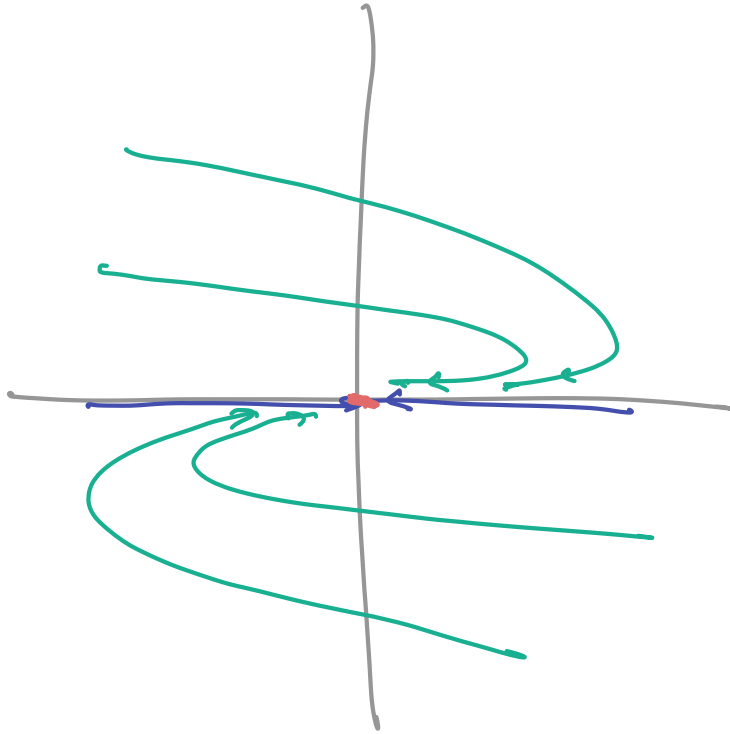
$$= \lambda P^{-1}IP + P^{-1}NP$$

$$= \lambda \begin{pmatrix} 1 & 0 \\ 0 & 1 \end{pmatrix} + P^{-1}NP$$

$$P^{-1}AP = P^{-1} \begin{pmatrix} a & 1 & 0 \\ & a & 0 \\ & & b \end{pmatrix} \quad X = P^{-1}y$$

$$A \begin{pmatrix} y_1 \\ y_2 \end{pmatrix}$$

$x < 0$



asymptotisch stabile Knoten

*Given:*  $\alpha + i\omega$  *Find:*  $u + iv$  :

$$\begin{aligned} A(u + iv) &= (\alpha + i\omega)(u + iv) \\ &= (\alpha u - \omega v) + i(\omega u + \alpha v) \end{aligned}$$

*Ans:*

$$Au = \alpha u - \omega v$$

$$Av = \omega u + \alpha v$$

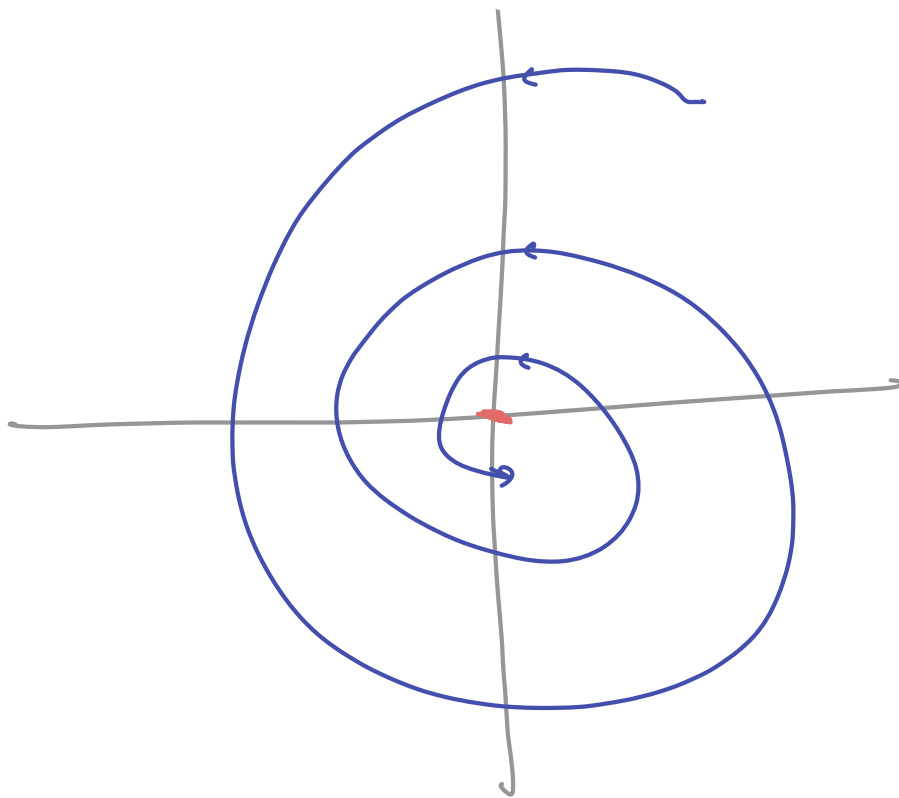
$G \rightarrow$  *Given*  $(u, v)$  *Get*  $\rightarrow$  *in*  $G \rightarrow$

$$A = \begin{pmatrix} \alpha & -\omega \\ \omega & \alpha \end{pmatrix} . \quad \text{Ans}$$

Draw plot

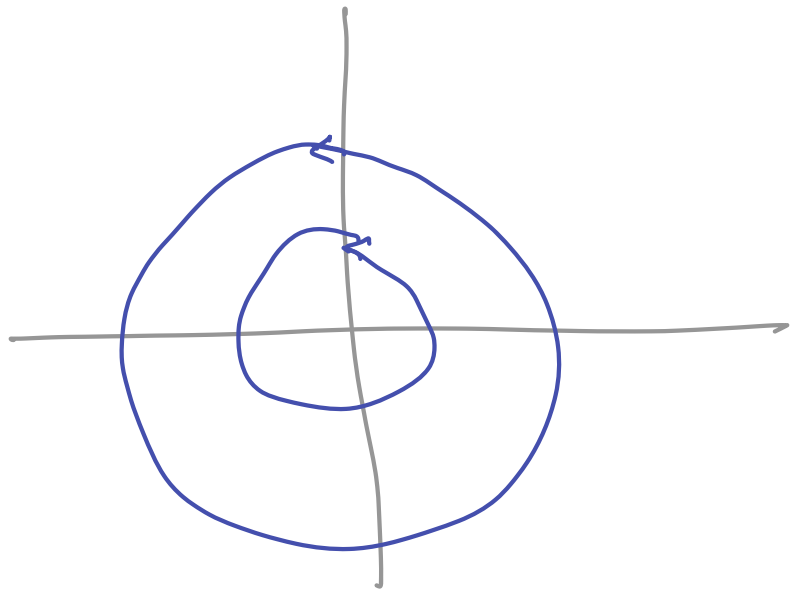


$\alpha < 0$



Stable Steady

$\alpha = 10$



*Zentrum*

