Math 2280-1
Monday November 24.

Homework due Dec. 1
6.3 8, 9, 10 14 15, 16 17
6.4 12 13, 14 15 16

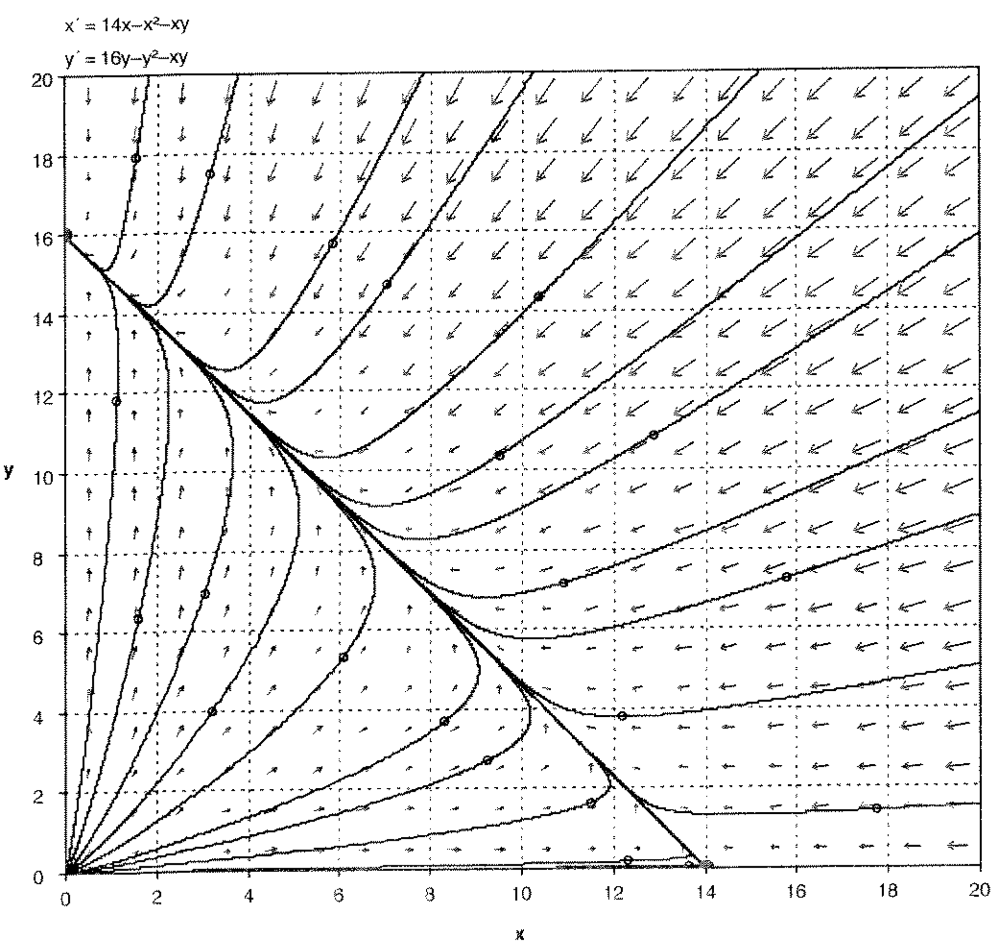
• §6.3 Analyze the general "competition" model, and the overly competitive example, pages 3-7 Friday notes.

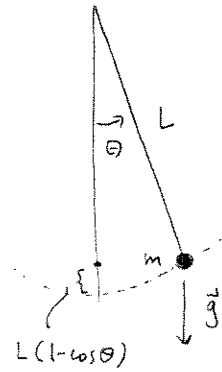
By the way, if you're having trouble visualizing the borderline case, here's our running example with $b_1 b_2 = c_1 c_2$

$b_1 b_2$ ↑ logistic params

$c_1 c_2$ ↑ competition params

Explain!





rigid-rod pendulum:

(1) $\Theta''(t) + \frac{g}{L}\sin\Theta = 0$

We derived this DE using
$KE + PE \equiv \text{constant}$
$\frac{1}{2}mL^2(\Theta')^2 + mgL(1-\cos\Theta) \equiv \text{const}$

(2) $\frac{1}{2}L(\Theta')^2 + g(1-\cos\Theta) \equiv \widetilde{\text{const}}$

(and we took $\frac{d}{dt}(\%)$ to get (1))

For
$x = \Theta(t)$
$y = \Theta'(t)$

$$\begin{bmatrix} x' \\ y' \end{bmatrix} = \begin{bmatrix} y \\ -\frac{g}{L}\sin x \end{bmatrix}$$

equil sol'ns $y = 0$
$\sin x = 0$: $x = k\pi,\ k \in \mathbb{Z}$ $(0, \pm 1, \pm 2, \dots)$

Linearization:

$$J = \begin{bmatrix} F_x & F_y \\ G_x & G_y \end{bmatrix} = \begin{bmatrix} 0 & 1 \\ -\frac{g}{L}\cos x & 0 \end{bmatrix}$$

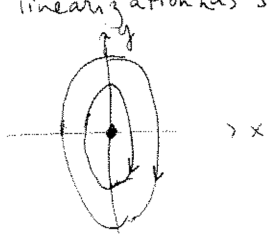
if $x = k\pi$ k <u>even</u>

$$J = \begin{bmatrix} 0 & 1 \\ -\frac{g}{L} & 0 \end{bmatrix}$$

$|J - \lambda I| = \lambda^2 + \left(\frac{g}{L}\right)^{\cancel{2}} = 0$

$\lambda = \pm i\sqrt{\frac{g}{L}}$

linearization has stable center



(why clockwise?)

if $x = k\pi$, k odd

$$J = \begin{bmatrix} 0 & 1 \\ \frac{g}{L} & 0 \end{bmatrix}$$

$|J - \lambda I| = \lambda^2 - \frac{g}{L} = 0$

$\lambda = \pm\sqrt{\frac{g}{L}}$ saddle

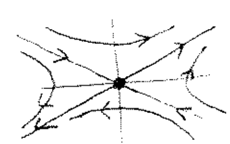
$\lambda = \sqrt{\frac{g}{L}}$

$$\left[\begin{array}{cc|c} -\sqrt{\frac{g}{L}} & 1 & 0 \\ \frac{g}{L} & -\sqrt{\frac{g}{L}} & 0 \end{array}\right]$$

$\vec{v} = \begin{bmatrix} 1 \\ \sqrt{\frac{g}{L}} \end{bmatrix}$

$\lambda = -\sqrt{\frac{g}{L}}$

$\vec{v} = \begin{bmatrix} -1 \\ \sqrt{\frac{g}{L}} \end{bmatrix}$



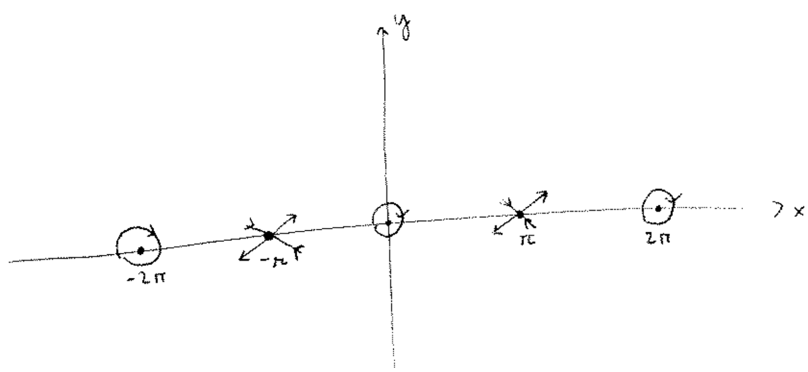
$\boxed{\text{fill in ?}}$

Hint: the trajectories must follow the level curves of the (scaled) total energy function (2), on page 1, i.e.

$$\frac{1}{2} L y^2 + g(1-\cos x) = \text{const} \longleftarrow \text{RHS is } 2\pi\text{-periodic in } x.$$

notice this function of (x,y) attains its minimum value of zero, at all $(x,y) = (k\pi, 0)$ with k even) (so $\cos x = 1$

and the Hessian matrix of this function is diagonal with positive diagonal entries, at these points, so the nearby trajectories for our system are (nearly) ellipses, for the non-linear system, so $(k\pi, 0)$ is stable center for the nonlinear problem, when k is even!



Add damping:

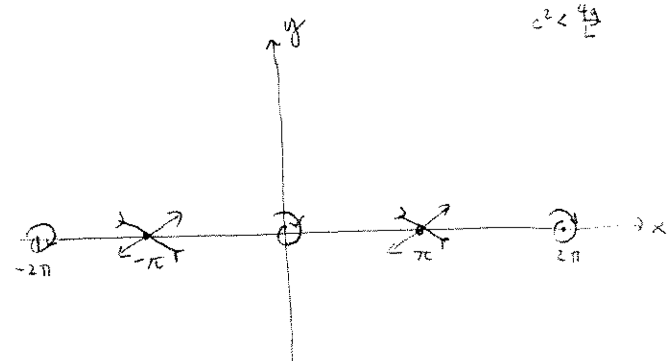
$$\Theta'' + c\Theta' + \frac{g}{L}\sin(\theta) = 0$$

$$\begin{bmatrix} x' \\ y' \end{bmatrix} = \begin{bmatrix} y \\ -\frac{g}{L}\sin x - cy \end{bmatrix}$$

Fill in?

same equilibria (iff $y=0$ & $\sin x = 0$)

$c^2 < \frac{4g}{L}$



$$J = \begin{bmatrix} F_x & F_y \\ G_x & G_y \end{bmatrix} = \begin{bmatrix} 0 & 1 \\ -\frac{g}{L}\cos x & -c \end{bmatrix}$$

$$|J - \lambda I| = -\lambda(-\lambda - c) + \frac{g}{L}\cos x$$

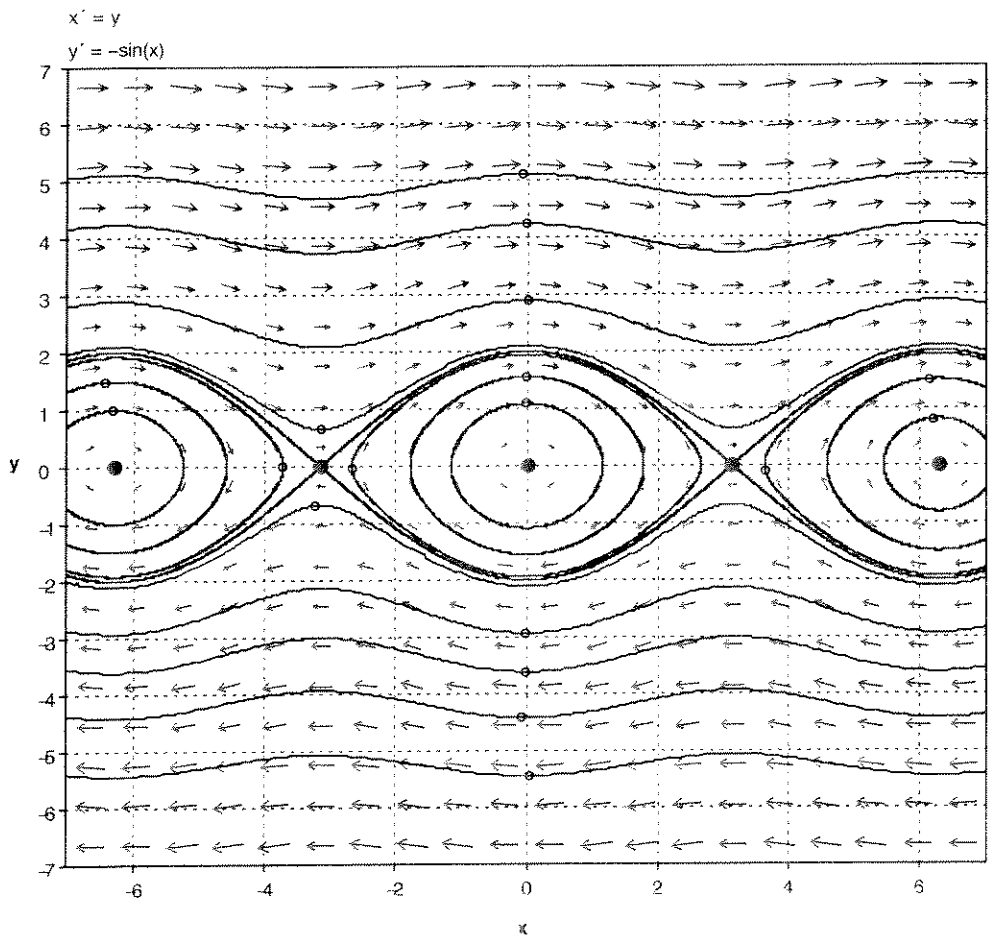
$$= \lambda^2 + c\lambda \pm \frac{g}{L} \qquad \begin{pmatrix} +\frac{g}{L} \text{ if } x = k\pi, \ k \text{ even} \\ -\frac{g}{L} \text{ if } k \text{ odd} \end{pmatrix}$$

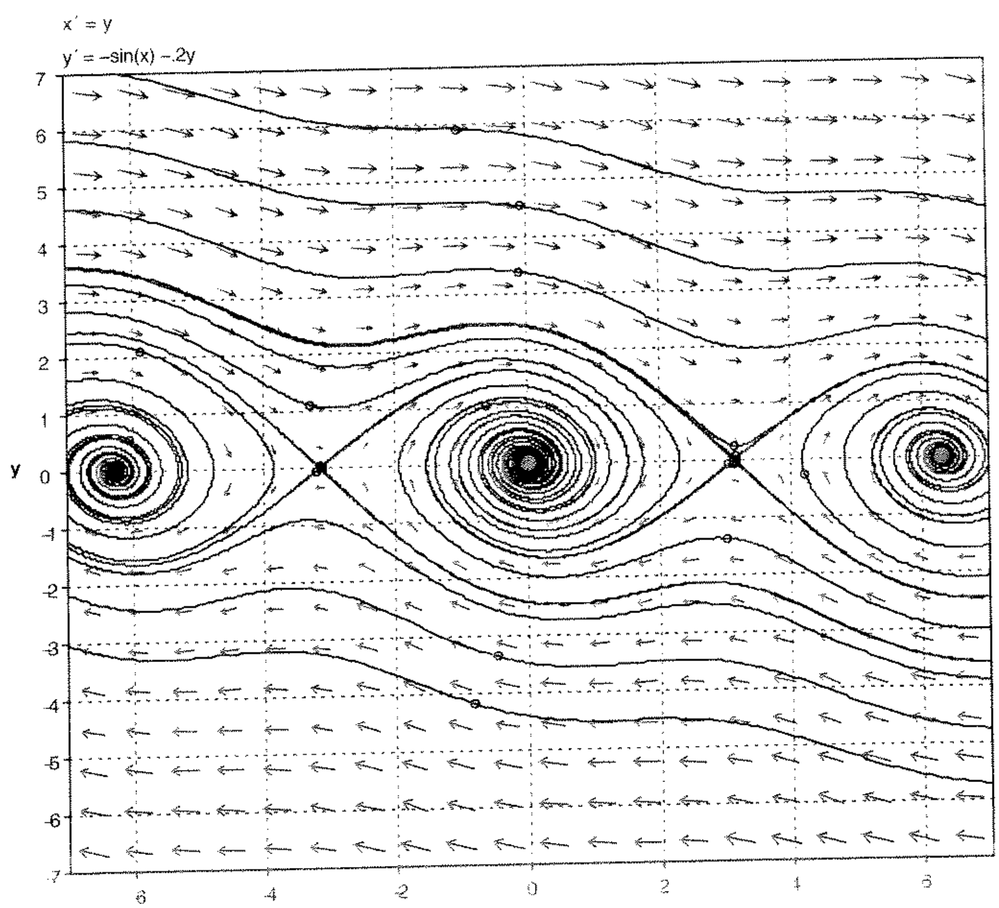
roots $\lambda = \dfrac{-c \pm \sqrt{c^2 \mp \frac{4g}{L}}}{2}$

k odd $\Rightarrow$ saddle

k even, $c^2 < \frac{4g}{L} \Rightarrow$ stable spiral (underdamped)

$c^2 > \frac{4g}{L} \Rightarrow$ stable node (overdamped) pictures for page 2-3:





nonlinear springs

$$m x'' = -cx' - kx + \beta x^3$$ (spring force is odd fcn; $F(-x) = -F(x)$)

$\beta > 0$ "soft spring"
$\beta < 0$ "hard spring"

Example 1 p 415-416

$$x'' + 4x - x^3 = 0 \qquad \left(\overset{c=0}{k=4,}\ \beta = 1\right)$$

has a E fcn which is constant along trajectories:

$$E = \tfrac{1}{2}(x')^2 + 2x^2 - \frac{x^4}{4} \equiv \text{const}$$

$$\begin{matrix} x = x \\ y = x' \end{matrix} \Rightarrow \begin{bmatrix} x' \\ y' \end{bmatrix} = \begin{bmatrix} y \\ x^3 - 4x \end{bmatrix}$$

equil: $\begin{bmatrix} 0 \\ 0 \end{bmatrix}, \begin{bmatrix} 2 \\ 0 \end{bmatrix}, \begin{bmatrix} -2 \\ 0 \end{bmatrix}$

you can do the linearization analysis & deduce the phase portrait page 416, and below
World such a spring make sense physically, at least for large x?