

## MATHEMATICAL METHODS IN ENGINEERING

This text focuses on a variety of topics in mathematics in common usage in graduate engineering programs including vector calculus, linear and nonlinear ordinary differential equations, approximation methods, vector spaces, linear algebra, integral equations, and dynamical systems. The book is designed for engineering graduate students who wonder how much of their basic mathematics will be of use in practice. Following development of the underlying analysis, the book takes students step-by-step through a large number of examples that have been worked in detail. Students can choose to go through each step or to skip ahead if they desire. After seeing all the intermediate steps, they will be in a better position to know what is expected of them when solving homework assignments and examination problems, and when they are on the job. Each chapter concludes with numerous exercises for the student that reinforce the chapter content and help connect the subject matter to a variety of engineering problems. Students today have grown up with computer-based tools including numerical calculations and computer graphics; the worked-out examples as well as the endof-chapter exercises often use computers for numerical and symbolic computations and for graphical display of the results.

Joseph M. Powers joined the University of Notre Dame in 1989. His research has focused on the dynamics of high-speed reactive fluids and on computational science, especially as it applies to verification and validation of complex multiscale systems. He has held positions at the NASA Lewis Research Center, the Los Alamos National Laboratory, the Air Force Research Laboratory, the Argonne National Laboratory, and the Chinese Academy of Sciences. He is a member of AIAA, APS, ASME, the Combustion Institute, and SIAM. He is the recipient of numerous teaching awards.

Mihir Sen has been active in teaching and in research in thermal-fluids engineering – especially in regard to problems relating to modeling, dynamics, and stability – since obtaining his PhD from MIT. He has worked on reacting flows, natural and forced convection, flow in porous media, falling films, boiling, MEMS, heat exchangers, thermal control, and intelligent systems. He joined the University of Notre Dame in 1986 and received the Kaneb Teaching Award from the College of Engineering in 2001 and the Rev. Edmund P. Joyce, C.S.C., Award for Excellence in Undergraduate Teaching in 2009. He is a Fellow of ASME.



## **Mathematical Methods in Engineering**

Joseph M. Powers University of Notre Dame

Mihir Sen University of Notre Dame







Shaftesbury Road, Cambridge CB2 8EA, United Kingdom

One Liberty Plaza, 20th Floor, New York, NY 10006, USA

477 Williamstown Road, Port Melbourne, VIC 3207, Australia

314-321, 3rd Floor, Plot 3, Splendor Forum, Jasola District Centre, New Delhi - 110025, India

103 Penang Road, #05-06/07, Visioncrest Commercial, Singapore 238467

Cambridge University Press is part of Cambridge University Press & Assessment, a department of the University of Cambridge.

We share the University's mission to contribute to society through the pursuit of education, learning and research at the highest international levels of excellence.

www.cambridge.org

Information on this title: www.cambridge.org/9781107037045

© Joseph M. Powers and Mihir Sen 2015

This publication is in copyright. Subject to statutory exception and to the provisions of relevant collective licensing agreements, no reproduction of any part may take place without the written permission of Cambridge University Press & Assessment.

First published 2015

A catalogue record for this publication is available from the British Library

Library of Congress Cataloging-in-Publication data

Powers, Joseph, 1961-

Mathematical methods in engineering / Joseph Powers, University of Notre Dame,

Mihir Sen, University of Notre Dame.

pages cm

Includes bibliographical references and index.

ISBN 978-1-107-03704-5 (hardback : alk. paper)

1. Engineering mathematics – Study and teaching (Graduate) I. Sen, Mihir, 1947–II. Title.

TA332.5.P69 2015

510-dc23 2014020962

ISBN 978-1-107-03704-5 Hardback

Cambridge University Press & Assessment has no responsibility for the persistence or accuracy of URLs for external or third-party internet websites referred to in this publication and does not guarantee that any content on such websites is, or will remain, accurate or appropriate.



To my parents: Mary Rita, my first reading teacher, and Joseph Leo, my first mathematics teacher – Joseph Michael Powers To my family: Beatriz, Pradeep, Maya, Yasamin, and Shayan – Mihir Sen



## **Contents**

Preface

1	Mu	Itivariable Calculus	1
	1.1	Implicit Functions	1
		1.1.1 One Independent Variable	1
		1.1.2 Many Independent Variables	5
		1.1.3 Many Dependent Variables	6
	1.2	Inverse Function Theorem	11
	1.3	Functional Dependence	13
	1.4	Leibniz Rule	18
	1.5	Optimization	20
		1.5.1 Unconstrained Optimization	21
		1.5.2 Calculus of Variations	22
		1.5.3 Constrained Optimization: Lagrange Multipliers	28
	1.6	Non-Cartesian Coordinate Transformations	31
		1.6.1 Jacobian Matrices and Metric Tensors	34
		1.6.2 Covariance and Contravariance	43
		1.6.3 Differentiation and Christoffel Symbols	49
		1.6.4 Summary of Identities	53
		1.6.5 Nonorthogonal Coordinates: Alternate Approach	54
		1.6.6 Orthogonal Curvilinear Coordinates	57
	Exe	ercises	59
2	Vec	ctors and Tensors in Cartesian Coordinates	64
	2.1	Preliminaries	64
		2.1.1 Cartesian Index Notation	64
		2.1.2 Direction Cosines	67
		2.1.3 Scalars	72
		2.1.4 Vectors	72
		2.1.5 Tensors	73
	2.2	Algebra of Vectors	81
		2.2.1 Definitions and Properties	81
		2.2.2 Scalar Product	82
		2.2.3 Cross Product	82

vii

page xiii



viii Contents

		2.2.4 Scalar Triple Product	83
		2.2.5 Identities	83
	2.3	Calculus of Vectors	84
		2.3.1 Vector Functions	84
		2.3.2 Differential Geometry of Curves	84
	2.4	Line Integrals	92
		Surface Integrals	94
	2.6	Differential Operators	94
		2.6.1 Gradient	95
		2.6.2 Divergence	98
		2.6.3 Curl	98
		2.6.4 Laplacian	99
		2.6.5 Identities	99
	2.7	Curvature Revisited	100
		2.7.1 Trajectory	100
		2.7.2 Principal	103
		2.7.3 Gaussian	103
	2.0	2.7.4 Mean	104
	2.8	Special Theorems 2.8.1 Green's Theorem	104
			104 105
		2.8.2 Divergence Theorem 2.8.3 Green's Identities	108
		2.8.4 Stokes' Theorem	108
		2.8.5 Extended Leibniz Rule	110
	Eve	ercises	110
	LAC	Cicises	11(
3	Firs	st-Order Ordinary Differential Equations	
3		st-Order Ordinary Differential Equations	
3	3.1		. 115
3	3.1 3.2	Paradigm Problem	. 115 115
3	3.1 3.2 3.3	Paradigm Problem Separation of Variables	. 115 115 117
3	3.1 3.2 3.3 3.4	Paradigm Problem Separation of Variables Homogeneous Equations	. 115 115 117 118
3	3.1 3.2 3.3 3.4 3.5	Paradigm Problem Separation of Variables Homogeneous Equations Exact Equations	. 115 115 117 118 120
3	3.1 3.2 3.3 3.4 3.5 3.6	Paradigm Problem Separation of Variables Homogeneous Equations Exact Equations Integrating Factors	. 115 115 117 118 120 122
3	3.1 3.2 3.3 3.4 3.5 3.6 3.7 3.8	Paradigm Problem Separation of Variables Homogeneous Equations Exact Equations Integrating Factors General Linear Solution Bernoulli Equation Riccati Equation	. 115 115 117 118 120 122 123
3	3.1 3.2 3.3 3.4 3.5 3.6 3.7 3.8	Paradigm Problem Separation of Variables Homogeneous Equations Exact Equations Integrating Factors General Linear Solution Bernoulli Equation	. 115 117 118 120 122 123
3	3.1 3.2 3.3 3.4 3.5 3.6 3.7 3.8	Paradigm Problem Separation of Variables Homogeneous Equations Exact Equations Integrating Factors General Linear Solution Bernoulli Equation Riccati Equation Reduction of Order 3.9.1 Dependent Variable y Absent	. 115 117 118 120 122 123 125 126 129
3	3.1 3.2 3.3 3.4 3.5 3.6 3.7 3.8 3.9	Paradigm Problem Separation of Variables Homogeneous Equations Exact Equations Integrating Factors General Linear Solution Bernoulli Equation Riccati Equation Reduction of Order 3.9.1 Dependent Variable y Absent 3.9.2 Independent Variable x Absent	. 115 115 117 118 120 123 125 126 129 129
3	3.1 3.2 3.3 3.4 3.5 3.6 3.7 3.8 3.9	Paradigm Problem Separation of Variables Homogeneous Equations Exact Equations Integrating Factors General Linear Solution Bernoulli Equation Riccati Equation Reduction of Order 3.9.1 Dependent Variable y Absent 3.9.2 Independent Variable x Absent Factorable Equations	. 115 115 117 118 120 122 123 125 126 129 129 131
3	3.1 3.2 3.3 3.4 3.5 3.6 3.7 3.8 3.9	Paradigm Problem Separation of Variables Homogeneous Equations Exact Equations Integrating Factors General Linear Solution Bernoulli Equation Riccati Equation Reduction of Order 3.9.1 Dependent Variable y Absent 3.9.2 Independent Variable x Absent D Factorable Equations Uniqueness and Singular Solutions	115 115 117 118 120 122 123 125 126 129 129 129 131 132
3	3.1 3.2 3.3 3.4 3.5 3.6 3.7 3.8 3.9	Paradigm Problem Separation of Variables Homogeneous Equations Exact Equations Integrating Factors General Linear Solution Bernoulli Equation Riccati Equation Reduction of Order 3.9.1 Dependent Variable y Absent 3.9.2 Independent Variable x Absent Diffractorable Equations Uniqueness and Singular Solutions Clairaut Equation	115 115 117 118 120 122 123 125 126 129 129 131 132 134
3	3.1 3.2 3.3 3.4 3.5 3.6 3.7 3.8 3.9 3.11 3.12 3.13	Paradigm Problem Separation of Variables Homogeneous Equations Exact Equations Integrating Factors General Linear Solution Bernoulli Equation Riccati Equation Reduction of Order 3.9.1 Dependent Variable y Absent 3.9.2 Independent Variable x Absent D Factorable Equations Uniqueness and Singular Solutions C Clairaut Equation B Picard Iteration	115 115 117 118 120 122 123 125 126 129 129 131 132 134 136
3	3.1 3.2 3.3 3.4 3.5 3.6 3.7 3.8 3.9 3.11 3.12 3.13 3.14	Paradigm Problem Separation of Variables Homogeneous Equations Exact Equations Integrating Factors General Linear Solution Bernoulli Equation Riccati Equation Reduction of Order 3.9.1 Dependent Variable y Absent 3.9.2 Independent Variable x Absent D Factorable Equations Uniqueness and Singular Solutions Clairaut Equation Picard Iteration Solution by Taylor Series	115 115 117 118 120 122 123 125 126 129 129 131 132 134 136 139
3	3.1 3.2 3.3 3.4 3.5 3.6 3.7 3.8 3.9 3.11 3.12 3.13 3.14 3.15	Paradigm Problem Separation of Variables Homogeneous Equations Exact Equations Integrating Factors General Linear Solution Bernoulli Equation Riccati Equation Reduction of Order 3.9.1 Dependent Variable y Absent 3.9.2 Independent Variable x Absent D Factorable Equations Uniqueness and Singular Solutions Clairaut Equation Sincard Iteration Solution by Taylor Series Delay Differential Equations	115 115 117 118 120 122 123 125 126 129 129 131 132 134 136 139 140
3	3.1 3.2 3.3 3.4 3.5 3.6 3.7 3.8 3.9 3.11 3.12 3.13 3.14 3.15	Paradigm Problem Separation of Variables Homogeneous Equations Exact Equations Integrating Factors General Linear Solution Bernoulli Equation Riccati Equation Reduction of Order 3.9.1 Dependent Variable y Absent 3.9.2 Independent Variable x Absent D Factorable Equations Uniqueness and Singular Solutions Clairaut Equation Picard Iteration Solution by Taylor Series	115 115 117 118 120 122 123 125 126 129 129 131 132 134 136 139
	3.1 3.2 3.3 3.4 3.5 3.6 3.7 3.8 3.9 3.11 3.12 3.13 3.14 3.15 Exe	Paradigm Problem Separation of Variables Homogeneous Equations Exact Equations Integrating Factors General Linear Solution Bernoulli Equation Riccati Equation Reduction of Order 3.9.1 Dependent Variable y Absent 3.9.2 Independent Variable x Absent D Factorable Equations Uniqueness and Singular Solutions Clairaut Equation Sincard Iteration Solution by Taylor Series Delay Differential Equations	115 115 117 118 120 122 123 125 126 129 129 131 132 134 136 139 140
	3.1 3.2 3.3 3.4 3.5 3.6 3.7 3.8 3.9 3.11 3.12 3.13 3.14 4.1	Paradigm Problem Separation of Variables Homogeneous Equations Exact Equations Integrating Factors General Linear Solution Bernoulli Equation Riccati Equation Reduction of Order 3.9.1 Dependent Variable y Absent 3.9.2 Independent Variable x Absent D Factorable Equations Uniqueness and Singular Solutions Clairaut Equation Picard Iteration Solution by Taylor Series Delay Differential Equations Ercises	115 115 117 118 120 122 123 125 126 129 129 131 132 134 136 139 140



Contents ix

		4.2.1 Constant Coefficients	149	
		4.2.2 Variable Coefficients	154	
	4.3	Particular Solutions	156	
		4.3.1 Undetermined Coefficients	156	
		4.3.2 Variation of Parameters	158	
		4.3.3 Green's Functions	160	
		4.3.4 Operator D	166	
	4.4	Sturm-Liouville Analysis	169	
		4.4.1 General Formulation	170	
		4.4.2 Adjoint of Differential Operators	171	
		4.4.3 Linear Oscillator	175	
		4.4.4 Legendre Differential Equation	179	
		4.4.5 Chebyshev Equation	182	
		4.4.6 Hermite Equation	185	
		4.4.7 Laguerre Equation	188	
		4.4.8 Bessel Differential Equation	189	
		Fourier Series Representation	193	
		Fredholm Alternative	200	
		Discrete and Continuous Spectra	201	
		Resonance	202	
		Linear Difference Equations	207	
	Exe	ercises	211	
5	Ap	proximation Methods	. 219	
	5.1	Function Approximation	220	
		5.1.1 Taylor Series	220	
		5.1.2 Padé Approximants	222	
	5.2	Power Series	224	
		5.2.1 Functional Equations	224	
		5.2.2 First-Order Differential Equations	226	
		5.2.3 Second-Order Differential Equations	230	
		5.2.4 Higher-Order Differential Equations	237	
	5.3	Taylor Series Solution	238	
	5.4	Perturbation Methods	240	
		5.4.1 Polynomial and Transcendental Equations	240	
		5.4.2 Regular Perturbations	244	
		5.4.3 Strained Coordinates	247	
		5.4.4 Multiple Scales	253	
		5.4.5 Boundary Layers	256	
		5.4.6 Interior Layers	261	
		5.4.7 WKBJ Method	263	
		5.4.8 Solutions of the Type $e^{S(x)}$	266	
		5.4.9 Repeated Substitution	267	
	5.5	Asymptotic Methods for Integrals	268	
	Exe	preises	271	
6	Linear Analysis			
	6.1	Sets	279	
	6.2	Integration	280	



x Contents

	6.3	Vector Spaces	283
		6.3.1 Normed	288
		6.3.2 Inner Product	297
	6.4	Gram-Schmidt Procedure	304
	6.5	Projection of Vectors onto New Bases	307
		6.5.1 Nonorthogonal	307
		6.5.2 Orthogonal	313
		6.5.3 Orthonormal	314
		6.5.4 Reciprocal	324
	6.6	Parseval's Equation, Convergence, and Completeness	330
	6.7	Operators	330
		6.7.1 Linear	332
		6.7.2 Adjoint	334
		6.7.3 Inverse	337
	6.8	Eigenvalues and Eigenvectors	339
	6.9	Rayleigh Quotient	350
	6.10	Linear Equations	354
	6.11	Method of Weighted Residuals	359
	6.12	Ritz and Rayleigh-Ritz Methods	371
	6.13	3 Uncertainty Quantification Via Polynomial Chaos	373
	Exe	ercises	379
7	Lin	ear Algebra	. 390
	7.1	Paradigm Problem	390
		Matrix Fundamentals and Operations	391
		7.2.1 Determinant and Rank	391
		7.2.2 Matrix Addition	392
		7.2.3 Column, Row, and Left and Right Null Spaces	392
		7.2.4 Matrix Multiplication	394
		7.2.5 Definitions and Properties	396
	7.3	Systems of Equations	399
		7.3.1 Overconstrained	400
		7.3.2 Underconstrained	403
		7.3.3 Simultaneously Over- and Underconstrained	405
		7.3.4 Square	406
		7.3.5 Fredholm Alternative	408
	7.4	Eigenvalues and Eigenvectors	410
		7.4.1 Ordinary	410
		7.4.2 Generalized in the Second Sense	414
	7.5	Matrices as Linear Mappings	415
	7.6	Complex Matrices	416
	7.7	Orthogonal and Unitary Matrices	419
		7.7.1 Givens Rotation	422
		7.7.2 Householder Reflection	423
	7.8	Discrete Fourier Transforms	426
	7.9	Matrix Decompositions	432
		$7.9.1  \mathbf{L} \cdot \mathbf{D} \cdot \hat{\mathbf{U}}$	432
		7.9.2 Cholesky	434
		7.9.3 Row Echelon Form	435



Contents xi

		7.9.4 <b>Q</b> · U	439
		7.9.5 Diagonalization	441
		7.9.6 Jordan Canonical Form	447
		7.9.7 Schur	449
		7.9.8 Singular Value	450
		7.9.9 Polar	453
		7.9.10 Hessenberg	456
		Projection Matrix	456
	7.11	Least Squares	458
		7.11.1 Unweighted	459
		7.11.2 Weighted	460
		2 Neumann Series	461
		3 Matrix Exponential	462
		4 Quadratic Form	464
		5 Moore-Penrose Pseudoinverse	467
	Exe	ercises	470
8	Lin	ear Integral Equations	. 480
	8.1	Definitions	480
	8.2	Homogeneous Fredholm Equations	481
		8.2.1 First Kind	481
		8.2.2 Second Kind	482
	8.3	Inhomogeneous Fredholm Equations	487
		8.3.1 First Kind	487
		8.3.2 Second Kind	489
	8.4	Fredholm Alternative	490
	8.5	Fourier Series Projection	490
	Exe	ercises	495
9	Dyı	namical Systems	. 497
	9.1	Iterated Maps	497
		Fractals	501
		9.2.1 Cantor Set	501
		9.2.2 Koch Curve	502
		9.2.3 Menger Sponge	502
		9.2.4 Weierstrass Function	503
		9.2.5 Mandelbrot and Julia Sets	503
	9.3	Introduction to Differential Systems	503
		9.3.1 Autonomous Example	504
		9.3.2 Nonautonomous Example	508
		9.3.3 General Approach	510
	9.4	High-Order Scalar Differential Equations	512
		Linear Systems	514
		9.5.1 Inhomogeneous with Variable Coefficients	514
		9.5.2 Homogeneous with Constant Coefficients	515
		9.5.3 Inhomogeneous with Constant Coefficients	525
	9.6	Nonlinear Systems	528
		9.6.1 Definitions	529
		9.6.2 Linear Stability	532



xii Contents

	9.6.3 Heteroclinic and Homoclinic Trajectories	533
	9.6.4 Nonlinear Forced Mass-Spring-Damper	539
	9.6.5 Lyapunov Functions	541
	9.6.6 Hamiltonian Systems	543
9.7	Differential-Algebraic Systems	545
	9.7.1 Linear Homogeneous	545
	9.7.2 Nonlinear	548
9.8	Fixed Points at Infinity	549
	9.8.1 Poincaré Sphere	549
	9.8.2 Projective Space	553
9.9	Bifurcations	554
	9.9.1 Pitchfork	555
	9.9.2 Transcritical	556
	9.9.3 Saddle-Node	557
	9.9.4 Hopf	558
	O Projection of Partial Differential Equations	559
9.1	1 Lorenz Equations	562
	9.11.1 Linear Stability	563
	9.11.2 Nonlinear Stability: Center Manifold Projection	565
	9.11.3 Transition to Chaos	569
Exc	ercises	573
Ap	pendix A	585
<b>A</b> .1	Roots of Polynomial Equations	585
	A.1.1 First-Order	585
	A.1.2 Quadratic	585
	A.1.3 Cubic	586
	A.1.4 Quartic	587
	A.1.5 Quintic and Higher	589
A.2	2 Cramer's Rule	589
A.3	3 Gaussian Elimination	590
A.4	Trapezoidal Rule	591
A.5	5 Trigonometric Relations	591
Α.6	Hyperbolic Functions	593
A.7	7 Special Functions	593
	A.7.1 Gamma	593
	A.7.2 Error	594
	A.7.3 Sine, Cosine, and Exponential Integral	594
	A.7.4 Hypergeometric	595
	A.7.5 Airy	596
	A.7.6 Dirac $\delta$ and Heaviside	596
A.8	3 Complex Numbers	598
	A.8.1 Euler's Formula	598
	A.8.2 Polar and Cartesian Representations	599
Exe	ercises	600
Bibliogi	ranhv	603
Index	~r··/	609



## **Preface**

Our overarching aim in writing this book is to build a bridge to enable engineers to better traverse the domains of the mathematical and physical worlds. Our focus is on neither the nuances of pure mathematics nor the phenomenology of physical devices but instead is on the mathematical tools used today in many engineering environments. We often compromise strict formalism for the sake of efficient exposition of mathematical tools. Whereas some results are fully derived, others are simply asserted, especially when detailed proofs would significantly lengthen the presentation. Thus, the book emphasizes method and technique over rigor and completeness; readers who require more of the latter can and *should* turn to many of the foundational works cited in the extensive bibliography.

Our specific objective is to survey topics in engineering-relevant applied mathematics, including multivariable calculus, vectors and tensors, ordinary differential equations, approximation methods, linear analysis, linear algebra, linear integral equations, and nonlinear dynamical systems. In short, the text fully explores linear systems and considers some effects of nonlinearity, especially those types that can be treated analytically. Many topics have geometric interpretations, identified throughout the book. Particular attention is paid to the notion of approximation via projection of an entity from a high- or even infinite-dimensional space onto a space of lower dimension. Another goal is to give the student the mathematical background to delve into topics such as dynamics, differential geometry, continuum mechanics, and computational methods; although the material presented is relevant to those fields, specific physical applications are mainly confined to some of the exercises. A final goal is to introduce the engineer to *some* of the notation and rigor of mathematics in a way used in many upper-level graduate engineering and applied mathematics courses.

This book is intended for use in a beginning graduate course in applied mathematics taught to engineers. It arose from a set of notes for such a course taught by the authors for more than 20 years in the Department of Aerospace and Mechanical Engineering at the University of Notre Dame. Students in this course come from a variety of backgrounds, mainly within engineering but also from science. Most enter with some undergraduate-level proficiency in differential and integral multivariable calculus, differential equations, vectors analysis, and linear algebra. This book briefly reviews these subjects but more often builds on an assumed elementary understanding of topics such as continuity, limits, series, and the chain rule.

xiii



xiv Preface

As such, we often casually introduce subject matter whose full development is deferred to later chapters. For example, although one of the key features of the book is a lengthy discussion of eigensystems in Chapter 6, most engineers will already know what an eigenvalue is. Consequently, we employ eigenvalues in nearly every chapter, starting from Chapter 1. The same can be said for topics such as vector operators, determinants, and linear equations. When such topics are introduced earlier than their formal presentation, we often make a forward reference to the appropriate section, and the student is encouraged to read ahead. In summary, most beginning graduate students and advanced undergraduates will be prepared for the subject matter, though they may find occasion to revisit some trusted undergraduate texts. Although our course is only one semester, we have added some topics to those we usually cover; the instructor of a similar course should be able to omit certain topics and add others.

At a time not very far in the past, mathematics in engineering was largely confined to basic algebra and interpolation of trigonometric and logarithmic tables. Not so today! Much of engineering has come to rely on sophisticated predictive mathematical models to design and control a wide variety of devices, for example, buildings and bridges, air and ground transportation, manufacturing and chemical processes, electrical and electronic devices, and biomedical and robotic equipment. These models may be in the form of algebraic, differential, integral, or other equations. Formulation of such models is often a challenge that calls on the basic sciences of physics, chemistry, and biology. Once they are formulated, the engineer is faced with actually solving the model equations, and for that a variety of tools are of value. Our focus is on the general mathematical tools used for engineering problems but not their formulation or specific physical details. While we sporadically discuss a paradigm problem such as a mass-spring-damper, we focus more on the mathematics. The use of mathematical analysis within engineering has changed greatly over the years. Once it was the sole means to the solution of some problems, but currently engineers rely on it within numerical and experimental approaches. The use of the adjective numerical has also changed over the years because of the variety of ways in which computers may be used in engineering. It is in fact becoming more common and necessary for extensive mathematical manipulation to be performed to prepare the computer for efficient and accurate solution generation.

Choices have been made with regard to notation; most of the conventions we adopt are reflected in at least a portion of the literature. In a few cases, we choose to diverge slightly from some of the more common norms. When we do so, explanatory footnotes are usually included. For example, the literature has a number of conventions for the so-called dot product or scalar product between two vectors, u and v. The most common is probably  $\mathbf{u} \cdot \mathbf{v}$ . We generally choose the more elaborate  $\mathbf{u}^T \cdot \mathbf{v}$ , where the T indicates a transpose operation. This emphasizes the fact that vectors are considered to be columns of elements and that to associate a scalar product of two vectors with the ordinary rules of matrix multiplication, one needs to transpose the first vector into a row of elements. Similarly, we generally take the product of a matrix A and vector  $\mathbf{u}$  to be of the form  $\mathbf{A} \cdot \mathbf{u}$  rather than the often-used  $\mathbf{A}\mathbf{u}$ . And we use  $\mathbf{u}^T \cdot \mathbf{A}$ , while many texts simply write  $\mathbf{u}\mathbf{A}$ . Unusually, we often apply the transpose notation to the so-called divergence operator, writing, for example, the divergence of a vector field  $\mathbf{u}$  as div  $\mathbf{u} = \nabla^T \cdot \mathbf{u}$  rather than as the more common  $\nabla \cdot \mathbf{u}$ . One could easily infer the nature of the divergence operation without the transpose, but we believe it adds unity to our notational framework. In the text,



Preface xv

italicized letters like a will most often be used for scalars, bold lowercase letters like a for vectors, bold uppercase letters like  $\bf A$  for tensors and operators, and  $\bf A$  for sets and spaces. In general, we use  $\bf ^T$  for transpose,  $\bf ^-$  for complex conjugate,  $\bf ^*$  for adjoint, and  $\bf ^H$  for Hermitian transpose. The student also has to be aware that the same quantities written on a blackboard or paper may appear differently. Whatever the notational choices, the student should be fluent in a variety of usages in the literature; we in fact sometimes deviate from our own conventions to reinforce that our choices are not unique.

Our experience has been that engineering students learn best by exposure to examples, and a hallmark of the text is that much of the material is developed via presentation of a large number of fully worked problems, each of which generally follows a short fundamental development. The solved examples not only illustrate the points made previously but also introduce additional concepts and are thus an integral part of the text. Ultimately, mathematics is learned by doing, and for this reason we have a large number of exercises. Engineers, moreover, have a special purpose for studying mathematics: they need it to solve practical problems; some are included as exercises.

Presentation of many of our specific details has relied on modern software for symbolic computation and plotting. We encourage the reader to utilize these tools as well, as they enable exact solutions and graphics that may otherwise be impossible. The text does not provide details of particular software packages, which often change with each new version; the reader is advised to choose one or more packages, such as Mathematica, Maple, or MATLAB, and to become familiar with its usage. Exercises are included that require the use of such software. The phrase "symbolic computer mathematics" is used to mean tools such as Mathematica or Maple and "discrete computational methods" to connote tools such as MATLAB, Python, Fortran, C, or C++. The problems emphasize plotting to give a geometric overview of the results. The use of visuals or graphics to get a quick appreciation for the quality of an approximation or the behavior of a result cannot be overemphasized.

There are a number of texts on graduate-level mathematics for engineers. Mathematics applied to engineering is a vast discipline; consequently, each book has a unique emphasis. Here we have attempted to include what is actually used by researchers in our field. To be clear, though, because it is for a one-semester introductory course, many topics are left for advanced courses. Among the topics omitted or lightly covered are integral transforms, complex variables, partial differential equations, group theory, probability, statistics, numerical methods, and graph and network theory.

In closing, we express our hope that the readers of this book will find mathematics to be as beautiful and useful a subject as we have over the years. Our appreciation was nurtured by a large number of special people: family members, teachers at all levels, colleagues at home and abroad, authors from many ages, and our own students over the decades. We have learned from all of them and hope that our propagation of their knowledge engenders new discoveries from readers of this book for future generations.

Joseph M. Powers Mihir Sen Notre Dame, Indiana, USA