

Contents

Chapter 1. The Tractrix and Similar Curves	1
1.1 Introduction	1
1.2 The Classical Tractrix	1
1.3 The Child and the Toy	3
1.4 The Jogger and the Dog	6
1.5 Showing the Motions with MATLAB	12
1.6 Jogger with Constant Velocity	15
1.7 Using a Moving Coordinate System	16
1.7.1 Transformation for Jogger/Dog	18
1.7.2 Transformation for Child/Toy	20
1.8 Examples	22
References	25
Chapter 2. Trajectory of a Spinning Tennis Ball . . .	27
2.1 Introduction	27
2.2 MAPLE Solution	29
2.3 MATLAB Solution	32
2.4 Simpler Solution for MATLAB 5	35
References	37
Chapter 3. The Illumination Problem	39
3.1 Introduction	39
3.2 Finding the Minimal Illumination Point on a Road	40
3.3 Varying h_2 to Maximize the Illumination	42
3.4 Optimal Illumination	45
3.5 Conclusion	49
References	49
Chapter 4. Orbits in the Planar Three-Body Problem	51
4.1 Introduction	51
4.2 Equations of Motion in Physical Coordinates	52
4.3 Global Regularization	56
4.4 The Pythagorean Three-Body Problem	62
4.5 Conclusions	70
References	72

Chapter 5. The Internal Field in Semiconductors . . .	73
5.1 Introduction	73
5.2 Solving a Nonlinear Poisson Equation Using MAPLE	74
5.3 MATLAB Solution	75
References	79
Chapter 6. Some Least Squares Problems	81
6.1 Introduction	81
6.2 Fitting Lines, Rectangles and Squares in the Plane	81
6.3 Fitting Hyperplanes	93
References	99
Chapter 7. The Generalized Billiard Problem	101
7.1 Introduction	101
7.2 The Generalized Reflection Method	101
7.2.1 Line and Curve Reflection	102
7.2.2 Mathematical Description	103
7.2.3 MAPLE Solution	104
7.3 The Shortest Trajectory Method	105
7.3.1 MAPLE Solution	106
7.4 Examples	106
7.4.1 The Circular Billiard Table	106
7.4.2 The Elliptical Billiard Table	110
7.4.3 The Snail Billiard Table	114
7.4.4 The Star Billiard Table	114
7.5 Conclusions	117
References	119
Chapter 8. Mirror Curves	121
8.1 The Interesting Waste	121
8.2 The Mirror Curves Created by MAPLE	121
8.3 The Inverse Problem	123
8.3.1 Outflanking Manoeuvre	123
8.3.2 Geometrical Construction of a Point on the Pattern Curve	124
8.3.3 MAPLE Solution	125
8.3.4 Analytic Solution	126
8.4 Examples	126
8.4.1 The Circle as the Mirror Curve	126
8.4.2 The Line as the Mirror Curve	128
8.5 Conclusions	129
References	132

Chapter 9. Smoothing Filters	133
9.1 Introduction	133
9.2 Savitzky-Golay Filter	133
9.2.1 Filter Coefficients	134
9.2.2 Results	137
9.3 Least Squares Filter	138
9.3.1 Lagrange Equations	139
9.3.2 Zero Finder	141
9.3.3 Evaluation of the Secular Function	142
9.3.4 MEX-Files	144
9.3.5 Results	148
References	150
Chapter 10. The Radar Problem	153
10.1 Introduction	153
10.2 Converting Degrees into Radians	154
10.3 Transformation into Geocentric Coordinates	155
10.4 The Transformations	158
10.5 Final Algorithm	160
10.6 Practical Example	160
References	162
Chapter 11. Conformal Mapping of a Circle	163
11.1 Introduction	163
11.2 Problem Outline	163
11.3 MAPLE Solution	164
11.4 MATLAB Solution	168
References	170
Chapter 12. The Spinning Top	171
12.1 Introduction	171
12.2 Formulation and Basic Analysis of the Solution	173
12.3 The Numerical Solution	178
References	180
Chapter 13. The Calibration Problem	181
13.1 Introduction	181
13.2 The Physical Model Description	181
13.3 Approximation by Splitting the Solution	184
13.4 Conclusions	189
References	190
Chapter 14. Heat Flow Problems	191
14.1 Introduction	191
14.2 Heat Flow through a Spherical Wall	191
14.2.1 A Steady State Heat Flow Model	192

14.2.2	Fourier Model for Steady State	193
14.2.3	MAPLE Plots	194
14.3	Non Stationary Heat Flow through an Agriculture Field	195
14.3.1	MAPLE Plots	199
	References	199
Chapter 15. Modeling Penetration Phenomena		201
15.1	Introduction	201
15.2	Short description of the penetration theory	201
15.3	The Tate-Alekseevskii model	203
15.3.1	Special case $R_t = Y_p$	205
15.3.2	Special case $\rho_p = \rho_t = \rho$	205
15.4	The eroding rod penetration model	207
15.5	Numerical Example	213
15.6	Conclusions	216
	References	216
Chapter 16. Heat Capacity of System of Bose Particles		219
16.1	Introduction	219
16.2	MAPLE Solution	221
	References	225
Chapter 17. Free Metal Compression		227
17.1	Introduction	227
17.2	The Base Expansion	229
17.3	Base Described by One and Several Functions	231
17.4	The Lateral Side Distortion	233
17.5	Non-centered Bases	237
17.6	Three Dimensional Graphical Representation of the Distorted Body	240
17.6.1	Centered base	240
17.6.2	Non-centered, Segmented Base	244
17.6.3	Convex Polygon Base	246
17.7	Three Dimensional Animation	247
17.8	Limitations and Conclusions	248
	References	250
Chapter 18. Gauss Quadrature		251
18.1	Introduction	251
18.2	Orthogonal Polynomials	252
18.3	Quadrature Rule	266
18.4	Gauss Quadrature Rule	267
18.5	Gauss-Radau Quadrature Rule	268

18.6 Gauss-Lobatto Quadrature Rule	271
18.7 Weights	274
18.8 Quadrature Error	275
References	278
Chapter 19. Symbolic Computation	
of Explicit Runge-Kutta Formulas	281
19.1 Introduction	281
19.2 Derivation of the Equations for the Parameters	283
19.3 Solving the System of Equations	285
19.3.1 Gröbner Bases	287
19.3.2 Resultants	290
19.4 The Complete Algorithm	292
19.4.1 Example 1:	292
19.4.2 Example 2:	293
19.5 Conclusions	296
References	297
Chapter 20. Transient Response of a	
Two-Phase Half-Wave Rectifier	299
20.1 Introduction	299
20.2 Problem Outline	299
20.3 Difficulties in Applying Conventional Codes	
and Software Packages	302
20.4 Solution by Means of MAPLE	304
References	310
Chapter 21. Circuits in Power Electronics	311
21.1 Introduction	311
21.2 Linear Differential Equations	
with Piecewise Constant Coefficients	313
21.3 Periodic Solutions	316
21.4 A MATLAB Implementation	317
21.5 Conclusions	322
References	322
Chapter 22. Newton's and Kepler's laws	323
22.1 Introduction	323
22.2 Equilibrium of Two Forces	323
22.3 Equilibrium of Three Forces	324
22.4 Equilibrium of Three Forces, Computed from	
the Potential Energy	326
22.5 Gravitation of the Massive Line Segment	328
22.5.1 Potential and Intensity	328
22.5.2 The Particle Trajectory	331

22.6	The Earth Satellite	333
22.7	Earth Satellite, Second Solution	334
22.8	The Lost Screw	336
22.9	Conclusions	337
	References	337
Chapter 23. Least Squares Fit of Point Clouds		339
23.1	Introduction	339
23.2	Computing the Translation	339
23.3	Computing the Orthogonal Matrix	340
23.4	Solution of the Procrustes Problem	341
23.5	Algorithm	342
23.6	Decomposing the Orthogonal Matrix	343
23.7	Numerical Examples	345
	23.7.1 First example	345
	23.7.2 Second example	348
	References	349
Chapter 24. Modeling Social Processes		351
24.1	Introduction	351
24.2	Modeling Population Migration	351
	24.2.1 Cyclic Migration without Regulation	353
	24.2.2 Cyclic Migration with Regulation	354
24.3	Modeling Strategic Investment	356
	References	358
Chapter 25. Contour Plots of Analytic Functions		359
25.1	Introduction	359
25.2	Contour Plots by the <code>contour</code> Command	359
25.3	Differential Equations	362
	25.3.1 Contour Lines $r = \text{const.}$	362
	25.3.2 Contour Lines $\varphi = \text{const.}$	364
25.4	The Contour Lines $r = 1$ of $f = e_n$	366
25.5	The Contour Lines $\varphi = \text{const}$ of $f = e_n$	370
	References	371
Chapter 26. Non Linear Least Squares: Finding the most accurate location of an aircraft		373
26.1	Introduction	373
26.2	Building the Least Squares Equations	374
26.3	Solving the Non-linear System	376
26.4	Confidence/Sensitivity Analysis	379

Chapter 27. Computing Plane Sundials	383
27.1 Introduction	383
27.2 Astronomical Fundamentals	383
27.2.1 Coordinate Systems	384
27.2.2 The Gnomonic Projection	386
27.3 Time Marks	388
27.3.1 Local Real Time	388
27.3.2 Mean Time	389
27.3.3 Babylonian and Italic Hours	394
27.4 Sundials on General Planes	395
27.5 A Concluding Example	396
References	398
Chapter 28. Agriculture Kinematics	399
28.1 Introduction	399
28.2 Modeling of the chain – Trajectory of the point G	400
28.3 Trajectory of point H – The lead end	401
28.4 Computing and Plotting Trajectory, Velocity and Acceleration of Scrapers	404
28.5 Plotting of the results	405
28.6 Rail Described by an Implicit Function	408
28.7 Hyperbola Rail (Implicit Function)	410
28.8 Rail Described by a Parametric Function	415
28.9 Hyperbola Rail (Parametric Function)	418
28.10 Conclusions	420
References	421
Chapter 29. The Catenary Curve	423
29.1 The Catenary Function	423
29.2 Scaling of the Problem	425
29.3 Eliminating Unknowns	426
29.4 Solution	427
29.5 Speed of Convergence	429
References	431
Chapter 30. Least Squares Fit with Piecewise Functions	433
30.1 Introduction	433
30.2 The Constrained Least Squares Problem	434
30.3 Gauss-Newton Solution	435
30.4 Structure of the Linearized Problem	436
30.5 The Main Program	438
30.6 Examples	441
30.7 Growth of Pigs	443
References	449

Chapter 31. Portfolio Problems – Solved Online . . .	451
31.1 The modified Markowitz model	451
31.2 Online solving	453
31.2.1 Downloading the Recorded Data	454
31.2.2 Computation of the Expected Returns and Volatilities of the Stocks	455
31.2.3 Defining the Mathematical Model	456
31.2.4 Solving the model with the <i>Nonlinear Pro-</i> <i>gramming</i> package	457
References	459
Appendix A. Shared knowledge of Maple and Matlab	461
A.1 Introduction	461
A.2 Application Centers	462
A.2.1 MAPLE Applications Center	462
A.2.2 MAPLE Student Center	462
A.2.3 MATLAB Student Center	463
A.2.4 MATLAB Faculty Center	463
A.2.5 MATLAB Central	463
A.3 Conclusions	464
Index	465
Index of used MAPLE Commands	471
Index of used MATLAB Commands	475