# Math 240: Systems of Differential Equations 

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## Outline

(1) Today's Goals

## (2) Distinct Eigenvalues

## Today's Goals

Combine linear algebra and differential equations to study systems of differential equations.
(1) Solve linear systems of differential equations using Eigenvalues.

## If $A \in M_{n}(\mathbb{R})$

Given a constant coefficient, linear, homogeneous, first-order system

$$
x^{\prime}=A x
$$

our intuition prompts us to guess a solution vector of the form

$$
\mathbf{x}=\left(\begin{array}{c}
k_{1} \\
k_{2} \\
\vdots \\
k_{n}
\end{array}\right) e^{\lambda t}=\mathbf{K} e^{\lambda t}
$$

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$$

Hence, we can find such a solution vector iff $K$ is an eigenvector for $A$ with eigenvalue $\lambda$.

## General Solution with Distinct Real Eigenvalues

## Theorem

Let $A \in M_{n}(\mathbb{R})$. If $A$ has $n$ linearly independent eigenvectors $v_{1}, v_{2}, \ldots, v_{n}$, with real eigenvalues $\lambda_{1}, \lambda_{2}, \ldots, \lambda_{n}$ (not necessarily distinct), then the general solution to $\mathbf{x}^{\prime}=\mathbf{A} \mathbf{x}$ on any interval is

$$
\mathbf{X}=c_{1} v_{1} e^{\lambda_{1} t}+c_{2} v_{2} e^{\lambda_{2} t}+\ldots+c_{n} v_{n} e^{\lambda_{n} t}
$$

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$$

Exercise: Solve the linear system $X^{\prime}=A X$ if

$$
A=\left(\begin{array}{ll}
-1 & 2 \\
-7 & 8
\end{array}\right)
$$

## Complex Eigenvalues

```
Theorem
Let }\lambda=a+bi be a complex eigenvalue of A with eigenvectors vi, .., v, v
where v}\mp@subsup{v}{j}{}=\mp@subsup{r}{j}{}+i\mp@subsup{s}{j}{}\mathrm{ . Then the 2k real valued linearly independent solutions
to }\mp@subsup{x}{}{\prime}=Ax\mathrm{ are:
eat}(\operatorname{cos}(bt)\mp@subsup{r}{1}{}+\operatorname{sin}(bt)\mp@subsup{s}{1}{}),\mp@subsup{e}{}{at}(\operatorname{cos}(bt)\mp@subsup{r}{2}{}+\operatorname{sin}(bt)\mp@subsup{s}{2}{}),\ldots,\mp@subsup{e}{}{at}(\operatorname{cos}(bt)\mp@subsup{r}{k}{}+\operatorname{sin}(bt
and
eat}(\operatorname{cos}(bt)\mp@subsup{r}{1}{}-\operatorname{sin}(bt)\mp@subsup{s}{1}{}),\mp@subsup{e}{}{at}(\operatorname{cos}(bt)\mp@subsup{r}{2}{}-\operatorname{sin}(bt)\mp@subsup{s}{2}{}),\ldots,\mp@subsup{e}{}{at}(\operatorname{cos}(bt)\mp@subsup{r}{k}{}-\operatorname{sin}(bt
```

