Example 83. Consider the system $\frac{dx}{dt} = 5x - y$, $\frac{dy}{dt} = 2y - 4x$.

(a) Determine the general solution.

(b) Make a phase portrait.

(c) Determine all equilibrium points and their stability.

Solution.

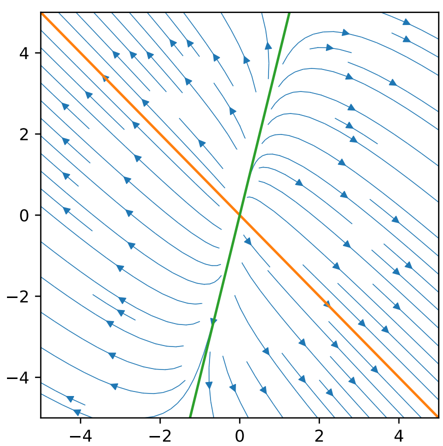
(a) Note that we can write this is in matrix form as $\begin{bmatrix} x \\ y \end{bmatrix}' = M\begin{bmatrix} x \\ y \end{bmatrix}$ with $M = -\begin{bmatrix} -5 & 1 \\ 4 & -2 \end{bmatrix}$, where the matrix is exactly -1 times what it was in Example 82.

Consequently, M has 1-eigenvector $\begin{bmatrix} 1 \\ 4 \end{bmatrix}$ as well as 6-eigenvector $\begin{bmatrix} -1 \\ 1 \end{bmatrix}$ (can you explain why the eigenvectors are the same and the eigenvalues changed sign?).

Thus, the general solution is $\begin{bmatrix} x(t) \\ y(t) \end{bmatrix} = C_1\begin{bmatrix} 1 \\ 4 \end{bmatrix}e^t + C_2\begin{bmatrix} -1 \\ 1 \end{bmatrix}e^{6t}$.

(b) We can have Sage make the plot for us:

```
>>> x,y = var('x y')
    plot = streamline_plot((5*x-y,-4*x+2*y), (x,-4,4), (y,-4,4))
```



Note that the phase portrait is identical to the one in Example 82, except that the arrows are reversed.

(c) The only equilibrium point is $(0,0)$ and it is unstable.

We can see this from the phase portrait but we can also see it readily from our general solution $\begin{bmatrix} x(t) \\ y(t) \end{bmatrix} = C_1\begin{bmatrix} 1 \\ 4 \end{bmatrix}e^t + C_2\begin{bmatrix} -1 \\ 1 \end{bmatrix}e^{6t}$ because e^t and e^{6t} go to ∞ as $t \to \infty$.

In general. If at least one eigenvalue is positive, then the equilibrium is unstable.

Example 84. Suppose the system $\frac{dx}{dt} = f(x,y)$, $\frac{dy}{dt} = g(x,y)$ has general solution $\begin{bmatrix} x(t) \\ y(t) \end{bmatrix} = C_1\begin{bmatrix} 1 \\ 4 \end{bmatrix}e^{-t} + C_2\begin{bmatrix} -1 \\ 1 \end{bmatrix}e^{6t}$. Determine all equilibrium points and their stability.

Solution. Clearly, the only constant solution is the zero solution $\begin{bmatrix} x(t) \\ y(t) \end{bmatrix} = \begin{bmatrix} 0 \\ 0 \end{bmatrix}$. Equivalently, the only equilibrium point is $(0,0)$.

Since $e^{6t} \to \infty$ as $t \to \infty$, we conclude that the equilibrium is unstable. (Note that the solution $C_2\begin{bmatrix} -1 \\ 1 \end{bmatrix}e^{6t}$ starts arbitrarily near to $(0,0)$ but always "flows away").

Excursion: Euler's identity

Theorem 85. (Euler's identity) $e^{ix} = \cos(x) + i\sin(x)$

Proof. Observe that both sides are the (unique) solution to the IVP $y' = iy$, $y(0) = 1$.
[Check that by computing the derivatives and verifying the initial condition! As we did in class.] □

On lots of T-shirts. In particular, with $x = \pi$, we get $\boxed{e^{\pi i} = -1}$ or $e^{i\pi} + 1 = 0$ (which connects the five fundamental constants).

Example 86. Where do trig identities like $\sin(2x) = 2\cos(x)\sin(x)$ or $\sin^2(x) = \frac{1 - \cos(2x)}{2}$ (and infinitely many others you have never heard of!) come from?

Short answer: they all come from the simple exponential law $e^{x+y} = e^x e^y$.

Let us illustrate this in the simple case $(e^x)^2 = e^{2x}$. Observe that

$$\begin{aligned} e^{2ix} &= \cos(2x) + i\sin(2x) \\ e^{ix}e^{ix} &= [\cos(x) + i\sin(x)]^2 = \cos^2(x) - \sin^2(x) + 2i\cos(x)\sin(x). \end{aligned}$$

Comparing imaginary parts (the "stuff with an i"), we conclude that $\sin(2x) = 2\cos(x)\sin(x)$.
Likewise, comparing real parts, we read off $\cos(2x) = \cos^2(x) - \sin^2(x)$.

(Use $\cos^2(x) + \sin^2(x) = 1$ to derive $\sin^2(x) = \frac{1 - \cos(2x)}{2}$ from the last equation.)

Challenge. Can you find a triple-angle trig identity for $\cos(3x)$ and $\sin(3x)$ using $(e^x)^3 = e^{3x}$?
Or, use $e^{i(x+y)} = e^{ix}e^{iy}$ to derive $\cos(x+y) = \cos(x)\cos(y) - \sin(x)\sin(y)$ and $\sin(x+y) = \ldots$ (that's what we actually did in class).

Realize that the complex number $e^{i\theta} = \cos(\theta) + i\sin(\theta)$ corresponds to the point $(\cos(\theta), \sin(\theta))$.
These are precisely the points on the unit circle!

Recall that a point (x, y) can be represented using **polar coordinates** (r, θ), where r is the distance to the origin and θ is the angle with the x-axis.

Then, $x = r\cos\theta$ and $y = r\sin\theta$.

Every complex number z can be written in **polar form** as $z = re^{i\theta}$, with $r = |z|$.

Why? By comparing with the usual polar coordinates ($x = r\cos\theta$ and $y = r\sin\theta$), we can write

$$z = x + iy = r\cos\theta + ir\sin\theta = re^{i\theta}.$$

In the final step, we used Euler's identity.

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