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MATHEMATICAL PHYSICS

Fourth Edition

B D Gupta

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*MATHEMATICAL
PHYSICS*

MATHEMATICAL PHYSICS

FOURTH EDITION

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VIKAS® Regd. Office: 576, Masjid Road, Jangpura, **New Delhi**-110 014

E-mail: helpline@vikaspublishing.com • www.vikaspublishing.com

- First Floor, N.S. Bhawan, 4th Cross, 4th Main, Gandhi Nagar, **Bengaluru**-560 009 • Phone: 080-22204639, 22281254
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First Edition, 1978

Fourth Edition, 2010

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Printed at Millenium Offset Pvt. Ltd., Delhi-110028

PREFACE TO THE FOURTH EDITION

I have once again availed the opportunity of revising this work, designed to suit the requirements of students of Applied Mathematics, Physics and Technical courses at both undergraduate and postgraduate levels. In the Third Edition, as required by the UGC syllabus as well as syllabi of several other universities of India many topics such as Conformal Mapping in Complex Analysis, Inversion of Complex Matrices, Error Functions, Factorial Functions, etc., and specially the solution of Schrödinger's Wave-equation in Quantum Mechanics, had been added. However a need was still felt to add some more useful topics to enhance the utility of the work, without going into competitive spirit to make it bulky as done at the primary levels, where there is almost a kind of competition to make the schoolbag heavier by putting into it, even bricks or rough and tough materials taken from any corner, without thinking whether the fabricated material matches the needs of the reader who may be an ordinary student or a researcher i.e., if the author himself is competent enough to undergo the research work.

In the present revised work, I have mainly touched upon the following topics for new additions and alterations:

- (i) *In Vectors*: Transformation of Coordinates of a vector on a change of bases, Rankine's Theorem, Helmholtz Theorem (*i.e.*, rigorous proof) and a few problems.
- (ii) *In Matrices*: A criterion on Solutions of Simultaneous Equations, some more methods of Matrix Inversion, other elegant methods of matrix-inversion along with the general eigenvalue problem and a few problems.
- (iii) *In Tensors*: Einstein Gravitational Equation and Equation of Planetary Orbits.
- (iv) *In Complex Analysis*: Natural Boundary Theorem (Lambert's Series), a new article on Convergence of Integrals, Series and Products along with uniform and Absolute Convergence, and a few problems.
- (v) *In Beta, Gamma and Error Functions*: Euler's product for $\Gamma(n)$ with different forms, convergence of Gamma Integrals, Values of $\Gamma\left(\frac{1}{2}\right)$ and $\Gamma'(1)$, convergence of Beta Integrals, Orthogonal Sets of Functions with Mean Square Error and Gram-Schmidt Ortho-Normalization and a few problems.
- (vi) *In Differential Equations*: Euler's Method with modifications, Taylor's Series Method and Runge's Method for solving First Order Differential Equations.
- (vii) *In Harmonics*: Some alternative approaches, Weber Bessel Functions, Neuman-Bessel Functions, Weber-Schlaflfli Functions, Lommet Theorem, Kelvin's Functions, Various Transformations, alternative solutions to Hermite Equation, other form of Hermite Polynomial along with Integral representation, Explanatory note on Integral Property of Laguerre Polynomials, altier to

Orthogonality of Laguerre Polynomials, Heaviside Unit Function, Hurwitz Formula, Debye Function and a few problems.

(viii) *In Appendices:* Approximate solutions of Algebraic and Transcendental Equations containing Graphic Method, Analytic Method, Newton-Raphson Method, Iterative Method (Linear Iteration method) and Regula-Falsi Method with illustrations.

References to examination papers have been at relevant places.

For this revision, I have freely consulted the contributions of Indian and foreign authors, in the form of the titles as *Mathematical Physics*, *Quantum Mechanics*, *Complex Analysis*, *Numerical Analysis* and *Mathematical Methods* with special functions. I am deeply grateful to the authors and publishers of all these books and my heartiest thanks to all of them.

I am also very thankful to the editorial team at Vikas Publishing House for taking keen interest in publishing the revised work well in time and in an attractive format.

I do hope that the work in its present form will be more useful to the readers for whom it is intended.

Although I have tried my best to make the work free from errors and omissions, but if the readers still find some misprints and take the pain of making me aware of them, then I shall feel personally obliged to them.

Any suggestions for further improvement of the work, such as the addition of any new topic or topics, will be thankfully accepted and executed.

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B D Gupta

PREFACE TO THE FIRST EDITION

It was in the year 1965, that myself and my colleague BS Rajput, wrote a book entitled *Mathematical Physics*, to meet the requirements of Honours, Postgraduate and Engineering students of various Indian universities. Since then the same work has appeared in six editions with the previous publisher. But for many reasons, we could not continue the co-authorship.

Here I would like to offer my sincere thanks to my former co-author and previous publisher for giving their consents to get it revised and published independently.

Now, keeping in mind the needs of the changing syllabi of various universities and the requirements of changing knowledge which almost doubles in every decade, I prepared this work myself about five years back, in view of new and advanced standpoint. But owing to some unavoidable circumstances this could not be published earlier, and so some of its portions have been further revised in order to render it up-to-date, hence more useful.

The value and scope of the present work have obviously been considerably increased, because, in the first place, several portions contributed by myself, in all my books written with different co-authors, have been reproduced in a more expository style and in the second place many more portions have been rewritten. The entire matter has been rearranged and many new topics have been added. Every section has been supplemented with a large number of worked-out problems and a set of additional miscellaneous problems selected from the question papers set in various university examinations.

I do not claim any originality of matter and this is at best a compiled work, with a novel presentation. The subject matter has been so arranged that even a layman can understand how to apply the mathematical operations to the problems of Physics. During the preparation of this work, I have freely consulted a number of books on Mathematics and Physics written by foreign and Indian authors. It goes without saying that I am deeply indebted to all of them, although, I am sorry not to acknowledge my gratitude to them individually—the number being too big to be accommodated in the little space that can be spared for that purpose in a work of the nature.

While revising the Volume, I have developed chapter one on ‘Vectors’ from all my contributions to our ‘Vector Analysis’, ‘Vector-Calculus’ and ‘Elements of Mechanics’, chapter two on ‘Matrices’ from my contributions to our ‘Mathematical Physics’, chapter three on ‘Tensors’ from my contributions to ‘Relativistic Mechanics’ after the publication of which a number of sections on tensors were taken to our ‘Mathematical Physics’, chapter four on ‘Group Theory’ (written a new); chapters five to ten on ‘Complex Variables’, ‘Beta’, Gamma and Error Functions’, ‘Differential Equations’, ‘Harmonics’, ‘Fourier Series’, ‘Integrals and Transforms’ and ‘Laplace’s Transforms’ from my contributions to our ‘Mathematical Physics’. Chapters eleven to fourteen on ‘Hankel Transforms’, ‘Diffusion, Wave and Laplace’s Equation’, ‘Maxwell’s Electromagnetic

Field Equations' and 'Special Theory of Relativity' have been written quite new. Chapter fifteen on 'Statistical Probability' has been developed from my contributions to our 'Mathematical Statistics'. In the end, the three Appendices A, B, C on 'Some formulated results in Basic Mathematics', 'Asymptotic Expansion of Error Function', and 'Character Tables in Group Theory' have been added in order to enhance the utility of the work.

In the preparation of Appendix C, I have been much guided by 'Elements of Group Theory for Physicists' by A. W. Joshi, Published by Wiley Eastern Ltd., New Delhi, I acknowledge my indebtedness to all my past and present co-authors, chiefly my colleagues Messrs O.P. Gupta, H.C. Sharma, J.P. Agarwal, Satya Parkash (formerly a student of mine), and the publisher M/s Kedar Nath Ram Nath, Meerut.

My thanks are also due to A.W. Joshi of the Institute of Advanced Studies, Meerut University and to Naresh Kumar, my colleague and a former pupil of mine, for their concrete suggestions during the preparation of this book. I would be failing in my duty if I do not acknowledge my deep gratitude to my colleagues P.C. Jain, M.P. Tyagi, B. Singh and V.P. Arora for not only rendering me their best help and cooperation but also encouraging and inspiring me all along.

Any suggestions for further improvement of the book from any corner will be thankfully accepted and executed.

B D Gupta

CONTENTS

<i>Preface to the fourth edition</i>	v
<i>Preface to the first edition</i>	vii
1. VECTORS	1.1–1.188
1.1. Introduction	1.1
1.2. Representation of vectors	1.1
1.3. Kinds of vectors	1.2
1.4. Addition of vectors	1.3
1.5. Subtraction of vectors	1.4
1.6. Multiplication of a vector by a scalar	1.5
1.7. Vector space or linear space	1.6
1.8. Conditions for a physical quantity to be representable by a vector	1.7
1.9. Resolution of vectors	1.8
1.10. Linear combination of vectors	1.18
1.11. Product of two vectors	1.21
1.12. Triple products of vectors	1.30
1.13. Product of four vectors	1.39
1.14. Reciprocal system of vectors	1.41
1.15. Vector equations	1.41
1.16. Simple applications of vectors to mechanics	1.43
1.17. Differentiation of vectors	1.50
1.18. Some rules for differentiation	1.51
1.19. Partial differentiation of vectors	1.61
1.20. Rules for partial differentiation of vectors	1.63
1.21. The scalar and vector fields	1.66
1.22. Directional derivatives	1.67
1.23. Level surfaces	1.69
1.24. The gradient of a scalar field	1.69
1.25. The gradient of a scalar-point function	1.71
1.26. The gradient of sum of two scalar-point functions	1.72
1.27. The gradient of product of two scalar-point functions	1.72
1.28. The divergence of a vector-point function	1.75
1.29. The divergence of sum of two vector functions	1.77
1.30. The divergence of product	1.77
1.31. The curl or rotation of a vector-point function	1.82
1.32. Curl of the sum of two vector-point functions	1.83
1.33. Curl of the product of two vector-point functions	1.84
1.34. To express gradient of scalar product in terms of curl	1.86

1.35.	To express divergence of vector products in terms of curl	1.87
1.36.	Curvilinear co-ordinates	1.104
1.37.	Orthogonal curvilinear co-ordinates.	1.105
1.38.	Condition for orthogonality	1.106
1.39.	Reciprocal sets of two triads of mutually orthogonal vectors	1.107
1.40.	Gradient in terms of orthogonal curvilinear coordinates	1.109
1.41.	Divergence in terms of orthogonal curvilinear coordinates	1.110
1.42.	Curl in terms of orthogonal curvilinear coordinates	1.111
1.43.	Laplacian (∇^2) in terms of orthogonal curvilinear coordinates	1.112
1.44.	Equivalent expressions for $\nabla \phi$, $\nabla \cdot F$ and $\nabla \times F$ in rectangular coordinates	1.112
1.45.	Cylindrical coordinates as a special curvilinear system	1.113
1.46.	Spherical polar coordinates as a special curvilinear system	1.114
1.47.	Integration of a vector	1.119
1.48.	The line integral	1.123
1.49.	The surface integrals	1.129
1.50.	The volume integrals	1.139
1.51.	Gauss' divergence theorem	1.144
1.52.	Deductions from Gauss' theorem	1.146
1.53.	Physical interpretation of Gauss' divergence theorem	1.147
1.54.	Gauss' theorem	1.147
1.55.	Two-Green's identities	1.149
1.56.	Green's theorem in the plane	1.155
1.57.	Vector forms of Green's theorem in the plane	1.156
1.58.	Green's formula	1.158
1.59.	Poisson's equation with its solution	1.160
1.60.	Laplace's equation with its solution	1.161
1.61.	Stoke's theorem in space	1.164
1.62.	Some theorems	1.173
1.63.	The classification of vector fields	1.176
1.64.	Helmholtz's theorem	1.177
	Additional Miscellaneous Problems	1.179
2.	MATRICES	2.1–2.163
2.1.	Definitions and notations	2.1
2.2.	Equality of matrices	2.3
2.3.	Addition of matrices	2.4
2.4.	Properties of matrix-addition	2.6
2.5.	Multiplication of matrices	2.10
2.6.	Properties of matrix-multiplication	2.11
2.7.	Partitioning of matrices	2.17
2.8.	Products of matrices by partitioning	2.18
2.9.	Special matrices with their properties	2.20
2.10.	Rank of a matrix	2.62
2.11.	Some theorems on rank	2.63

2.12.	Solutions of linear equations	2.73
2.13.	Methods for solving linear equations	2.73
2.14.	Characteristic matrix and characteristic equation of a matrix	2.97
2.15.	Sub-spaces and null spaces	2.100
2.16.	Transformations	2.104
2.17.	Hermitian forms	2.107
2.18.	Characteristic roots and vectors of a matrix (Eigen values and Eigen vectors)	2.108
2.19.	Quadratic forms and their reductions	2.127
2.20.	Differentiation and integration of matrices	2.133
2.21.	Solution of a system of linear equations using differentiation of matrices	2.135
2.22.	Other element methods of matrix inversion	2.135
2.23.	The eigen-value problem	2.147
	Additional Miscellaneous Problems	2.159
3.	TENSORS	3.1–3.86
3.1.	Introduction	3.1
3.2.	Transformation of coordinates	3.3
3.3.	The summation convention and Kronecker delta symbol	3.4
3.4.	Tensors as classification of transformation laws	3.5
3.5.	Symmetric and anti-symmetric tensors	3.9
3.6.	Invariant tensors	3.13
3.7.	Rules which govern tensor analysis	3.19
3.8.	The fundamental tensors	3.28
3.9.	Associated tensors: Raising and lowering of suffixes	3.33
3.10.	Length of a vector, (<i>i.e.</i> , a tensor of rank one), angle between two vectors and orthogonality of vectors	3.35
3.11.	Metric tensor, Riemannian spaces	3.36
3.12.	Christoffel's 3-index symbols	3.38
3.13.	Equations of a geodesic	3.41
3.14.	Law of transformation for Christoffel's symbols	3.43
3.15.	Parallel displacement of vectors	3.47
3.16.	Covariant derivative of a vector	3.49
3.17.	Covariant derivative of a tensor	3.52
3.18.	The curvature, tensor (Riemann-Christoffel tensor)	3.57
3.19.	Riemann-Christoffel tensor or covariant curvature tensor	3.59
3.20.	Some important results	3.63
3.21.	Tensor forms of operators	3.65
3.22.	Einstein gravitational equation	3.65
	Additional Miscellaneous Problems	3.74
4.	GROUP THEORY	4.1–4.86
4.1.	Introduction to sets, mappings and binary operations	4.1
4.2.	Groups	4.13

4.3.	Elementary properties of a group	4.14
4.4.	Some definitions	4.16
4.5.	The centre of a group	4.27
4.6.	Cosets or cosets of a subgroup	4.27
4.7.	Cyclic group	4.31
4.8.	Permutation or transformation	4.34
4.9.	Homomorphism and isomorphism of groups	4.38
4.10.	Normals and conjugate subgroups	4.45
4.11.	Complexes and kernel	4.49
4.12.	Groups of isometries	4.55
4.13.	Some special groups with linear operators	4.61
4.14.	Permutational representations	4.72
	Additional Miscellaneous Problems	4.80
5.	COMPLEX VARIABLES	5.1–5.155
5.1.	Introduction	5.1
5.2.	Definitions	5.1
5.3.	Operation of fundamental laws of algebra on complex numbers	5.1
5.4.	Graphical representation (Argand diagram)	5.4
5.5.	Properties of moduli and arguments and geometry of complex numbers	5.19
5.6.	Regular functions	5.16
5.7.	Elementary functions and mapping by them	5.30
5.8.	Complex integration	5.37
5.9.	Cauchy's theorem	5.40
5.10.	Cauchy's integral formula	5.45
5.11.	Some results based on Cauchy's integral formula	5.47
5.12.	Taylor's expansion	5.49
5.13.	Laurent's expansion	5.51
5.14.	Residue and contour integration	5.62
5.15.	Cauchy's residue theorem	5.62
5.16.	Another important theorem	5.64
5.17.	Computation of residue	5.65
5.18.	Integration round the unit circle	5.67
5.19.	Evaluation of $\int_{-\infty}^{+\infty} f(x) dx$	5.68
5.20.	Jordan's lemma to evaluate infinite integrals	5.70
5.21.	Analytic continuation	5.107
5.22.	Conformal mapping	5.113
5.23.	Convergence of integrals, series and products	5.123
	Additional Miscellaneous Problems	5.143
6.	BETA, GAMMA AND ERROR FUNCTIONS	6.1–6.52
6.1.	Definitions	6.1
6.2.	Fundamental property of gamma functions	6.2
6.3.	The value of $\Gamma_{\frac{1}{2}}$ and graph of the gamma function	6.6

6.4.	Transformation of gamma function	6.8
6.5.	To show that $\beta(m, n) = \beta(n, m)$	6.9
6.6.	Different forms of Beta function	6.10
6.7.	To find the relation between beta and gamma functions	6.10
6.8.	Reduction of definite integrals to gamma functions	6.12
6.9.	Miscellaneous propositions	6.15
6.10.	Error function or probability integral	6.28
6.11.	Factorial function	6.30
6.12.	Some allied functions	6.34
6.13.	Orthogonal sets of functions	6.38
	Additional Miscellaneous Problems	6.47
7.	DIFFERENTIAL EQUATIONS	7.1–7.76
7.1.	Introduction	7.1
7.2.	Solution in simple cases of ordinary differential equations of second order	7.2
7.3.	Simple problems from physics	7.11
7.4.	Partial differential equations	7.15
7.5.	Special types of differential equations arising in physics	7.26
7.6.	Finite differences	7.31
7.7.	Polynomial interpolation	7.36
7.8.	Interpolation with equal intervals (<i>i.e.</i> when function-values are given at equidistant intervals)	7.36
7.9.	Interpolation with unequal intervals	7.41
7.10.	Central difference formulae	7.46
7.11.	Approximate integration	7.52
7.12.	Perturbation method	7.71
	Additional Miscellaneous Problems	7.75
8.	HARMONICS (WITH SPECIAL FUNCTIONS)	8.1–8.169
8.1.	Introduction	8.1
8.2.	Methods of integration in series	8.3
8.3.	Legendre differential equation, functions and polynomials with properties	8.16
8.4.	Bessel's equation, functions and polynomials	8.48
8.5.	Hypergeometric or Gauss equation and functions	8.84
8.6.	Confluent hypergeometric equations and functions	8.105
8.7.	Hermite equation, functions and polynomials	8.113
8.8.	Laguerre equation and polynomials with properties	8.129
8.9.	Riccati's differential equation	8.143
8.10.	The Dirac-delta function with its formal properties	8.147
8.11.	Riemann-Zeta function	8.151
	Additional Miscellaneous Problems	8.153

9. FOURIER'S SERIES, INTEGRALS AND TRANSFORMS	9.1–9.64
9.1. Definition and expansion of a function of x	9.1
9.2. Dirichlet's conditions	9.4
9.3. Assumptions for the validity of Fourier's series expansion, with allied theorems	9.5
9.4. Complex representation of a Fourier's series	9.11
9.5. Parseval's identity for Fourier series	9.28
9.6. Fourier's integral	9.29
9.7. Different forms of Fourier's integrals	9.32
9.8. A remark on convergence of Fourier's series	9.34
9.9. Physical applications of Fourier's series	9.36
9.10. The Fourier transforms	9.43
9.11. Applications of Fourier transforms to boundary value problems	9.55
Additional Miscellaneous Problems	9.60
10. THE LAPLACE TRANSFORMS	10.1–10.62
10.1. Introduction	10.1
10.2. Definition of the integral transform	10.1
10.3. Deduction of the definition of the Laplace transform from that of the integral transform	10.1
10.4. Definition of the Laplace transform	10.2
10.5. Functions of exponential order	10.6
10.6. Piecewise or sectional continuity	10.8
10.7. A function of class A	10.9
10.8. Sufficient conditions for the existence of Laplace transforms	10.9
10.9. Some properties of Laplace transforms	10.12
10.10. Some methods for finding Laplace transforms	10.20
10.11. The Laplace transforms of some special functions	10.22
10.12. Evaluation of integrals with the help of Laplace transforms	10.27
10.13. Laplace transform of the Laplace transform	10.28
10.14. The inverse Laplace transform	10.29
10.15. Some properties of inverse Laplace transform	10.30
10.16. Evaluation of some integrals by inverse Laplace transforms	10.37
10.17. Some methods for finding inverse Laplace transform	10.40
10.18. Applications of Laplace transforms to differential equations	10.46
10.19. Applications of Laplace transforms to boundary value problems	10.51
10.20. The complex inversion formula or inversion theorem	10.55
Additional Miscellaneous Problems	10.61
11. HANKEL TRANSFORMS	11.1–11.23
11.1. Introduction	11.1
11.2. Definition of infinite Hankel transform	11.4
11.3. Inverse formula for Hankel transform	11.5
11.4. Parseval's theorem for Hankel transforms	11.8
11.5. Linearity property	11.8
11.6. Hankel transform of the derivatives of a function	11.8

11.7.	Hankel transforms of $\frac{d^2 f}{dx^2}$, $\frac{d^2 f}{dx^2} + \frac{1}{x} \frac{df}{dx}$ and $\frac{d^2 f}{dx^2} + \frac{1}{x} \frac{df}{dx} - \frac{n^2}{x^2} f$ under certain conditions	11.10
11.8.	Applications to boundary value problems	11.12
11.9.	Finite Hankel transforms	11.13
11.10.	Finite Hankel transform of $\frac{df}{dx}$, p being root of $J_n(p) = 0$	11.17
11.11.	Finite Hankel transform of $\frac{d^2 f}{dx^2} + \frac{1}{x} \frac{df}{dx}$	11.17
11.12.	Finite Hankel transform of $\frac{d^2 f}{dx^2} + \frac{1}{x} \frac{df}{dx} - \frac{n^2}{x^2} f(x)$ p being a root of $J_n(pa) = 0$	11.20
	Additional Miscellaneous Problems	11.21
12.	DIFFUSION, WAVE AND LAPLACE'S EQUATIONS	12.1–12.73
12.1.	Introduction	12.1
12.2.	Diffusion equation of Fourier equation of heat flow	12.1
12.3.	One-dimensional diffusion equation $\frac{\partial \mathbf{u}}{\partial t} = h^2 \frac{\partial^2 \mathbf{u}}{\partial x^2} = k \frac{\partial^2 \mathbf{u}}{\partial x^2}$	12.3
12.4.	Two-dimensional diffusion equation <i>i.e.</i> , $\frac{\partial \mathbf{u}}{\partial t} = h^2 \left(\frac{\partial^2 \mathbf{u}}{\partial x^2} + \frac{\partial^2 \mathbf{u}}{\partial y^2} \right)$	12.13
12.5.	Three-dimensional diffusion equation	12.16
12.6.	Laplace's equation	12.17
12.7.	Two-dimensional Laplace's equation (steady flow of heat)	12.17
12.8.	Three-dimensional of Laplace's equation	12.26
12.9.	General properties of Harmonic functions	12.33
12.10.	The wave equations	12.35
12.11.	Green's functions for the wave equation	12.38
12.12.	Homogeneous and inhomogeneous wave equations	12.41
12.13.	Theory of wave guides	12.44
12.14.	Solution of one-dimensional wave equation	12.46
12.15.	Square wave	12.52
12.16.	Solution of two-dimensional wave equation	12.54
12.17.	Solution of three-dimensional wave equation	12.60
	Additional Miscellaneous Problems	12.66
13.	MAXWELL'S ELECTROMAGNETIC FIELD EQUATIONS	13.1–13.10
13.1.	Introduction	13.1
13.2.	Maxwell's equations for electromagnetic field	13.2
13.3.	To show $\nabla \cdot \mathbf{D} = 4\pi\rho$	13.3
13.4.	To show $\text{div } \mathbf{B} = 0$	13.4
13.5.	To show $\text{curl } \mathbf{E} = -\frac{1}{c} \frac{\partial \mathbf{B}}{\partial t}$	13.4

13.6.	Physical Interpretation of Maxwell's Equations	13.5
13.7.	Decaying of free charge	13.6
13.8.	Poynting vector	13.6
13.9.	Poynting theorem	13.8
	Additional Miscellaneous Problems	13.10
14.	SPECIAL THEORY OF RELATIVITY	14.1–14.27
14.1.	Introduction	14.1
14.2.	Basic postulates of special theory of relativity	14.3
14.3.	Lorentz transformations	14.3
14.4.	The Kinematic effects of the Lorentz transformations	14.9
14.5.	Energy-Momentum relation	14.19
	Additional Miscellaneous Problems	14.27
15.	STATISTICAL PROBABILITY	15.1–15.150
15.1.	Introduction	15.1
15.2.	Definitions of probability	15.2
15.3.	Events	15.7
15.4.	Theorem of total probability, <i>i.e.</i> , additive law of probability	15.7
15.5.	Theorem of compound probability or multiplicative law of probability	15.11
15.6.	Probability: A new standpoint	15.16
15.7.	Repeated trials: Binomial and multinomial expansions	15.32
15.8.	Measures of central tendency	15.38
15.9.	Measures of dispersion (or variation)	15.54
15.10.	Moments	15.67
15.11.	Expectation	15.72
15.12.	Continuous univariate probability distribution	15.82
15.13.	Tchebycheff's Inequality	15.89
15.14.	Characteristic function	15.93
15.15.	Fourier's inversion theorem	15.93
15.16.	Theoretical distributions	15.95
15.17.	Other distributions	15.124
15.18.	The principle of least squares	15.129
15.19.	Correlation and regression	15.133
15.20.	Sampling distributions	15.141
15.21.	Theory of errors	15.146
	Additional Miscellaneous Problems	15.149
APPENDICES		A.1–A.33
A.	Some formulated results in basic mathematics	A.1
B.	Asymptotic expansion of error function	A.12
C.	Character tables in group theory	A.14
D.	Approximate solutions of algebraic and transcendental equations	A.24
INDEX		I.1–I.14



Vectors

1.1 INTRODUCTION

It is generally observed that there exist two types of physical measurements in applied mathematics, physics and mechanics: one involving *only magnitude and no direction* in the space of three dimensions, such as volume, mass, length, speed, temperature, potential, electric charge, etc., and the other involving *a definite direction in space associated with their magnitudes* such as velocity, acceleration, momentum, force, electric or magnetic field intensities, etc., the former being called *scalar quantities* or simply *scalars* and the latter, *vector quantities* or simply *Vectors*.

A little consideration will exhibit that the complete characterisation of a scalar quantity requires length and support, *i.e.*, a specified unit and a number stating how many times that unit is contained in that quantity, while the complete characterisation of a vector quantity requires length, support and sense, *i.e.*, a specified unit, a number stating how many times that unit is contained in that quantity and the statement of the direction.

Stating in a precise manner a *vector* means '*a directed line segment*'. In other words we can state that a vector is a quantity having direction as well as magnitude. In Astronomy a vector means an imaginary straight line that joins a planet moving round a centre (generally the focus of an elliptic orbit) to that centre.

1.2 REPRESENTATION OF VECTORS

Since a vector is the result of abstraction, its magnitude and direction may be represented by a line OP directed from the *initial point* O to the *terminal point* P and denoted by \vec{OP} . Here the length of vector \vec{OP} denoted by $|\vec{OP}| = OP$ is called *magnitude* or *module* or *modulus* of the vector and the direction in space is indicated by an arrow head on the line.

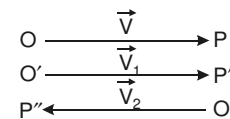


Fig. 1.1

In Fig. 1.1, the vector \vec{OP} has been shown by \vec{V} (or in Clarendon print by \mathbf{V}) while its scalar magnitude is stated by V . Thus OP is the length of the vector \mathbf{V} , while the line of indefinite length of which the directed line segment \vec{OP} is only a part is the support of \mathbf{V} and the sense is from O to P .

It should be noted that formulation of a law of physics in terms of vectors is however independent of the choice of axes of reference, *i.e.*, the vector representation has a physical content without reference to any coordinate system.

1.3 KINDS OF VECTORS

Equal vectors. Two given vectors may be equal only when they have the same magnitude and the same direction, *i.e.*, the given two vectors are equal if and only if they have the same or parallel support with equal length and the same sense. For example in Fig. 1.1, we have

$$\mathbf{V} (= \vec{OP}) = \mathbf{V}_1 (= \vec{O'P'}) = -\mathbf{V}_2 (= \vec{O''P''})$$

where \mathbf{V}_1 and \mathbf{V}_2 have the same scalar magnitude as \mathbf{V} but \mathbf{V}_1 has the same and \mathbf{V}_2 the opposite sense to that of \mathbf{V} .

Null vector. A vector having the initial and the terminal points coincident is termed as a *zero vector* or a *null vector*. Thus a null vector has its module zero.

Unit vector. A vector having its modulus as unity is called a *unit vector*.

If \mathbf{a} is a vector and 'a' its modulus, then unit vector \mathbf{a} is denoted by $\hat{\mathbf{a}}$ (read as 'a hat' or 'a caret') defined as

$$\hat{\mathbf{a}} = \frac{\mathbf{a}}{|\mathbf{a}|} = \frac{\mathbf{a}}{a}$$

Polar vectors. The line vectors representing the quantities like force, velocity, etc., in which merely a linear action in a particular direction is involved, are termed as *polar* vectors.

Axial vectors. The line vectors representing the quantities like angular velocity, angular acceleration, etc., in which some rotational action is involved about an axis and which are drawn parallel to the axis of rotation in order that the magnitude of the quantity is determined by the length of the vector and the direction by the rule of right handed screw (*i.e.*, rotation being considered in clockwise direction), are termed as *axial* vectors.

Free vector. Evidently a vector can be represented by an infinite number of equal vectors by drawing parallel supports. Such a vector which can be transported from place to place such that it remains of the same magnitude and keep up the same direction is termed as a *free* vector. In fact a free vector is assumed to remain the same through transportation, irrespective of its position in space.

Localised or Line vector. We have defined that the value of a free vector depends only on its length and direction, but if it depends also on its position in space, *i.e.*, if a vector is restricted to pass through a given origin, then it is termed as a *localised* vector.

Collinear vectors. The vectors parallel to the same line, regardless of their magnitudes and sense of directions are termed as *collinear* vectors. In other words the vectors having the same or parallel supports are known as collinear vectors. Such vectors are parallel to each other and they may coincide in a special case. As such there exists a scalar ratio say λ between any two collinear vectors \mathbf{a} and \mathbf{b} of the form

$$\mathbf{b} = \lambda \mathbf{a}$$

which follows that one of the two collinear vectors can be expressed as the scalar multiple of the other.

Non-collinear vectors. The vectors whose directions are neither parallel nor coincident are said to be *non-collinear*.

Like vectors or co-directional vectors. The vectors which are collinear and have the same sense of directions, *i.e.*, the vectors directed in the same sense irrespective of their magnitudes are termed as *like* vectors.

Unlike vectors. The vectors which are collinear but have opposite sense of directions from each other are termed as *unlike* vectors.

Coplanar vectors. A system of vectors lying in the parallel planes or which can be made to lie in the same plane are said to be *coplanar* vectors. Evidently any two vectors are always coplanar.

Non-coplanar vectors. A system of vectors consisting of three or more vectors which cannot be made to lie in the same plane are called *non-coplanar* vectors.

Reciprocal vector. Any vector having its direction the same as that of a given vector \mathbf{a} , but its magnitude as the reciprocal of the magnitude of \mathbf{a} is termed as the *reciprocal* vector of \mathbf{a} and written as \mathbf{a}^{-1} or $\frac{1}{\mathbf{a}}$. As such

$$\mathbf{a}^{-1} = \frac{1}{a} \hat{\mathbf{a}} = \frac{\mathbf{a}}{a^2} \hat{\mathbf{a}} = \frac{\mathbf{a}}{a^2} \quad (\text{by definition of a unit vector}).$$

In this connection it is notable that the magnitude and so the reciprocal of the magnitude of a unit vector being unity, the unit vector is reciprocal to itself and it is said to be *self-reciprocal*.

Negative vector. The vector having the same magnitude as the vector \mathbf{a} but opposite direction, is known as the *negative* of \mathbf{a} and written as $-\mathbf{a}$.

Position vector. If a vector \vec{OP} specifies the position of a point relative to an arbitrarily chosen point O , then \vec{OP} is called the *Position* vector of P with respect to O , the origin of vectors.

Problem 1. If $\{\mathbf{a}, \mathbf{b}, \mathbf{c}\}$ is a right handed set, which of the following sets are right handed?

(i) $\mathbf{a}, \mathbf{c}, \mathbf{b}$; (ii) $\mathbf{b}, \mathbf{c}, \mathbf{a}$; (iii) $\mathbf{b}, \mathbf{a}, \mathbf{c}$; (iv) $\mathbf{c}, \mathbf{a}, \mathbf{b}$; (v) $\mathbf{c}, \mathbf{b}, \mathbf{a}$.

It is clear that the sets (ii) and (iv), i.e., $\mathbf{b}, \mathbf{c}, \mathbf{a}$; and $\mathbf{c}, \mathbf{a}, \mathbf{b}$ are right handed.

Problem 2. Discuss the geometrical significance of $a\mathbf{A} + b\mathbf{B} = 0$.

We have $a\mathbf{A} + b\mathbf{B} = 0$, a, b being scalars.

$$\begin{aligned} \text{This can be written as } \mathbf{A} &= -\frac{b}{a}\mathbf{B} \\ &= \lambda\mathbf{B} \quad \text{if } \lambda = -\frac{b}{a} \end{aligned}$$

i.e., \mathbf{A} is expressible as a scalar multiple of \mathbf{B} so that the vectors \mathbf{A} and \mathbf{B} are parallel or collinear.

1.4 ADDITION OF VECTORS

The characterisation of process of summation is inherited in the composition of two or more displacements of a point. Suppose that we have two vectors \mathbf{a} and \mathbf{b} acting at a point O as shown in Fig. 1.2. Let $\vec{OA} = \mathbf{a}$ and $\vec{OB} = \mathbf{b}$.

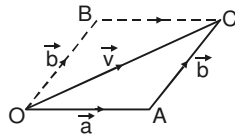


Fig. 1.2

Clearly the resultant effect of the vectors \mathbf{a} and \mathbf{b} is the same as that of their vector sum \mathbf{v} obtained by setting off the vector \mathbf{b} at the end of \mathbf{a} and then joining the beginning of \mathbf{a} to the end of \mathbf{b} . This geometrical construction utilised to find the vector sum of two vectors \mathbf{a} and \mathbf{b} is known as the *parallelogram law of addition of vectors*.

$$\text{Thus } \mathbf{v} = \vec{OC} = \vec{OA} + \vec{AC} = \mathbf{a} + \mathbf{b} \quad \dots (1)$$

A similar result follows by starting with \mathbf{b} and setting off the vectors \mathbf{a} on \mathbf{b} , i.e.,

$$\mathbf{v} = \vec{OC} = \vec{OB} + \vec{BC} = \mathbf{b} + \mathbf{a} \quad \dots (2)$$

Conclusively the result of adding two co-initial vectors is the vector represented by the diagonal of the parallelogram having the two given vectors as its adjacent sides.

From (1) and (2), it follows that

$$\mathbf{a} + \mathbf{b} = \mathbf{b} + \mathbf{a}$$

i.e., the two vectors obey the **commutative law of addition**, according to which the vector sum of two vectors is independent of their order.

We now propose to find the sum of three vectors say \mathbf{a} , \mathbf{b} , \mathbf{c} . Let $\vec{OA} = \mathbf{a}$, $\vec{AB} = \mathbf{b}$, $\vec{BC} = \mathbf{c}$ as shown in Fig. 1.3. Then

$$\mathbf{v} = \vec{OC} = \vec{OA} + \vec{AB} + \vec{BC} = \mathbf{a} + \mathbf{b} + \mathbf{c}. \quad \dots (3)$$

Also

$$\begin{aligned} \mathbf{v} &= \vec{OC} = \vec{OB} + \vec{BC} \\ &= (\vec{OA} + \vec{AB}) + \vec{BC} \\ &= (\mathbf{a} + \mathbf{b}) + \mathbf{c}. \end{aligned} \quad \dots (4)$$

Similarly

$$\mathbf{v} = \mathbf{a} + (\mathbf{b} + \mathbf{c}) \quad \dots (5)$$

and

$$\mathbf{v} = (\mathbf{a} + \mathbf{c}) + \mathbf{b} \quad \dots (6)$$

It follows from (3), (4), (5) and (6) that

$$\mathbf{v} = \mathbf{a} + \mathbf{b} + \mathbf{c} = (\mathbf{a} + \mathbf{b}) + \mathbf{c} = \mathbf{a} + (\mathbf{b} + \mathbf{c}) = (\mathbf{a} + \mathbf{c}) + \mathbf{b}.$$

i.e., the three vectors obey the **associative law of addition**, according to which the vector sum of three vectors is independent of the mode in which component vectors are associated in different groups.

In general, if there are n vectors \mathbf{a} , \mathbf{b} , \mathbf{c} , ..., \mathbf{n} , then their vector sum \mathbf{v} is given by

$$\mathbf{v} = \mathbf{a} + \mathbf{b} + \mathbf{c} + \dots + \mathbf{n}$$

1.5 SUBTRACTION OF VECTORS

If there are two vectors \mathbf{a} and \mathbf{b} , then

$$\mathbf{a} - \mathbf{b} = \mathbf{a} + (-\mathbf{b}),$$

i.e., the subtraction of \mathbf{b} from \mathbf{a} may be regarded as the addition of $-\mathbf{b}$ to \mathbf{a} . Thus, to subtract \mathbf{b} from \mathbf{a} , reverse the direction of \mathbf{b} and add to \mathbf{a} (Fig. 1.4).

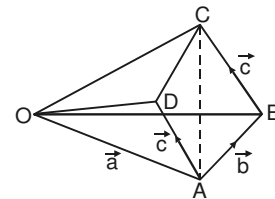


Fig. 1.3

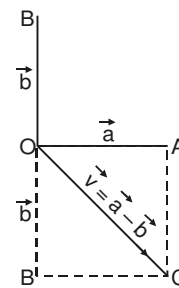
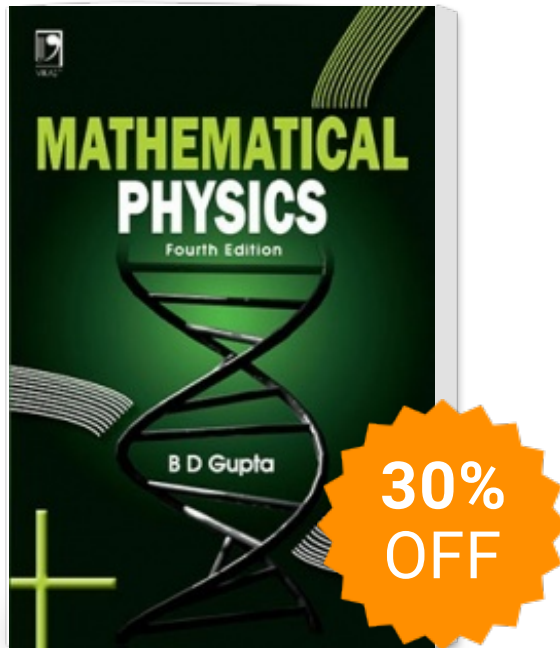


Fig. 1.4

Mathematical Physics



Publisher : SChand Publishing

ISBN : 9788125930969

Author : B D Gupta

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