

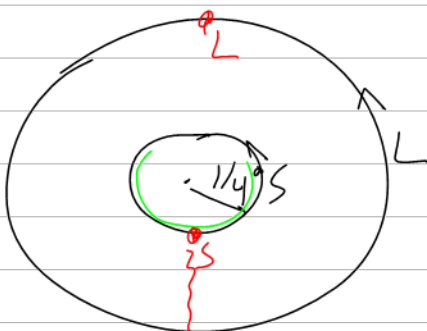
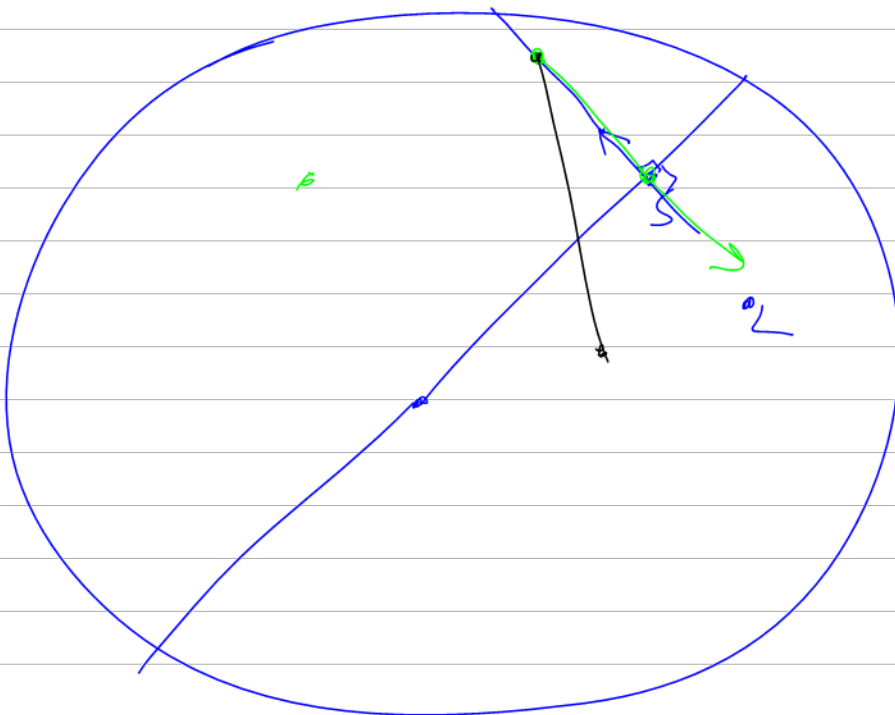
$$b_{i+1} = b_i + a_i^2$$

$$b_{n+1} = b_0 + \sum_{i=1}^n a_i^2 < 1$$

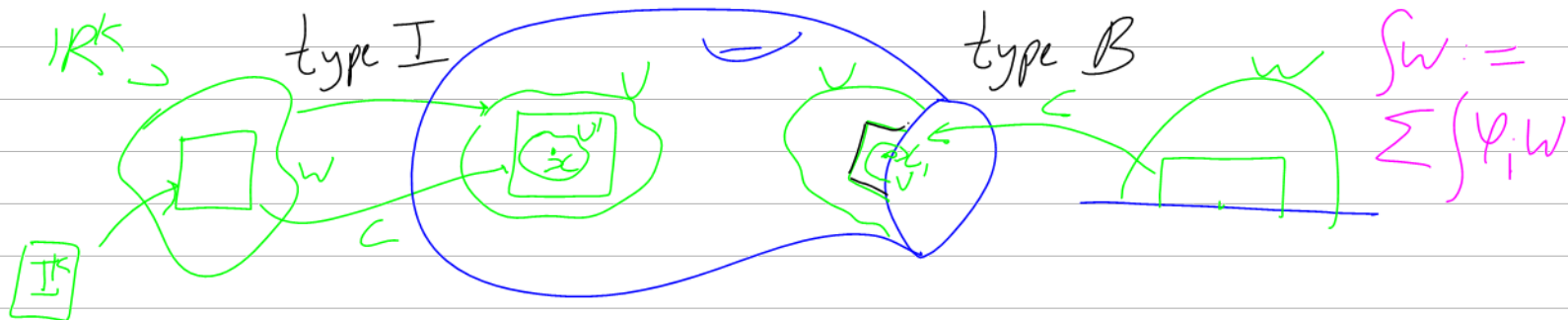
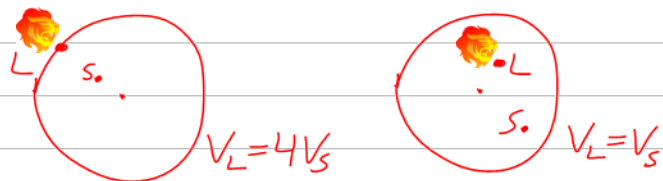
$$b_0 + \sum a_i^2 < 1$$

$$\sum a_i = \infty$$

$$a_k = \frac{1}{k+c}$$



$$0.75 < \frac{\pi}{4}$$



Stokes' Thm IF M is compact and oriented &
 $w \in \mathcal{L}^{k-1}(M)$, then $\int_M dw = \int_{\partial M} w$
PF for type B $w \in \mathcal{L}^{k-1}(M)$, $\text{supp } w \subset U'$ (type B)

$$\int_M dw = \int_C dw = \int_{I^k} C^* dw = \int_{I^k} d(C^* w) = \int_{\partial I^k} C^* w$$

$$= - \int_{I^k_{(1,0)}(y_1, \dots, y_{k-1})} C^* w = + \int_{\partial M} w$$

PF of Thm (assembly)

$$\int_M w = \sum_i \int_M \varphi_i w = \sum_i \int_M d(\varphi_i w)$$

$$d\varphi_i \wedge w + \varphi_i dw$$

$$= \sum_i \int_M d\psi_i \wedge \omega + \sum_i \int_M \psi_i d\omega$$

$$\int_M d\left(\sum_i \psi_i\right) \wedge \omega \quad \int_M d\omega$$

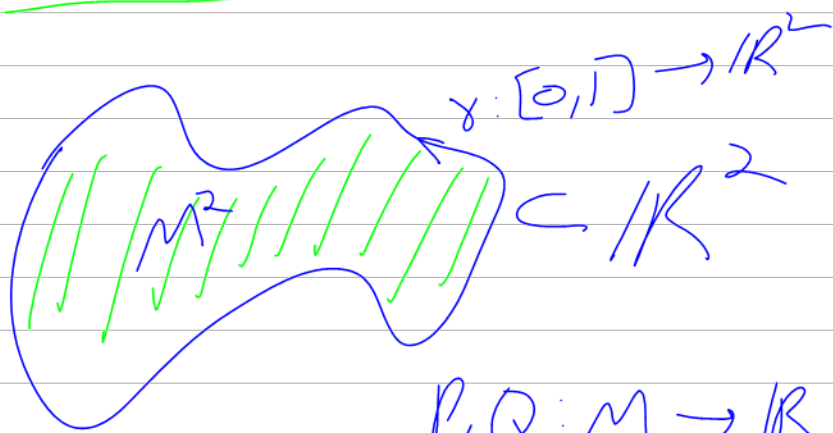
$$\int_M \theta \wedge \omega = 0.$$

□

Example $M = [a, b]$ $\omega = F \in \mathcal{C}^0([a, b])$

$$\int_a^b F' dx = \int_{[a, b]} dF = \int_{[a, b]} F = F(b) - F(a)$$

Funer than of calculus.



M : connected
simply connected
domain in \mathbb{R}^2
w/ bdy \sim smooth
curve γ .

$$P, Q: M \rightarrow \mathbb{R}$$

$$\omega = P dx + Q dy \in \mathcal{L}^1(M)$$

$$d\omega = \left(\frac{\partial Q}{\partial x} - \frac{\partial P}{\partial y} \right) dx \wedge dy$$

$$\int_M \left(\frac{\partial Q}{\partial x} - \frac{\partial P}{\partial y} \right) dx dy = \int_\gamma P dx + Q dy$$

$t \in [0,1] \quad \gamma(t) = \begin{pmatrix} x_1(t) \\ x_2(t) \end{pmatrix}$

$$= \int_{[0,1]} \gamma^* (P dx + Q dy)$$

$$dx = dx_1(t) = x_1'(t) dt$$

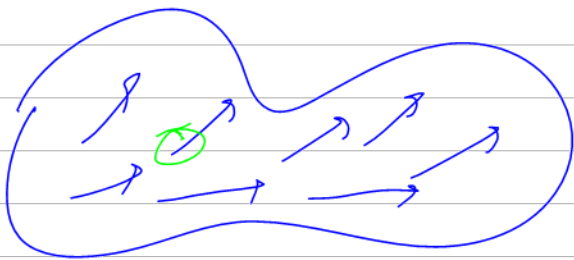
$$= \int_{[0,1]} P(\gamma(t)) \cdot x_1'(t) dt + Q(\gamma(t)) \cdot x_2'(t) dt$$

$$= \int_{[0,1]} \begin{pmatrix} P \\ Q \end{pmatrix} \cdot \underbrace{\begin{pmatrix} x_1' \\ x_2' \end{pmatrix}}_{\dot{\gamma}} dt = \int_{[0,1]} \begin{pmatrix} P \\ Q \end{pmatrix} \cdot \dot{\gamma} dt$$

$$\int_{[0,1]} \begin{pmatrix} P \\ Q \end{pmatrix} \cdot \dot{\gamma} dt = \int_M \left(\frac{\partial Q}{\partial x} - \frac{\partial P}{\partial y} \right) dx dy$$

Two interpretations:

"curl": $\begin{pmatrix} P \\ Q \end{pmatrix}$: a vector Field on \mathbb{R}^2 or M



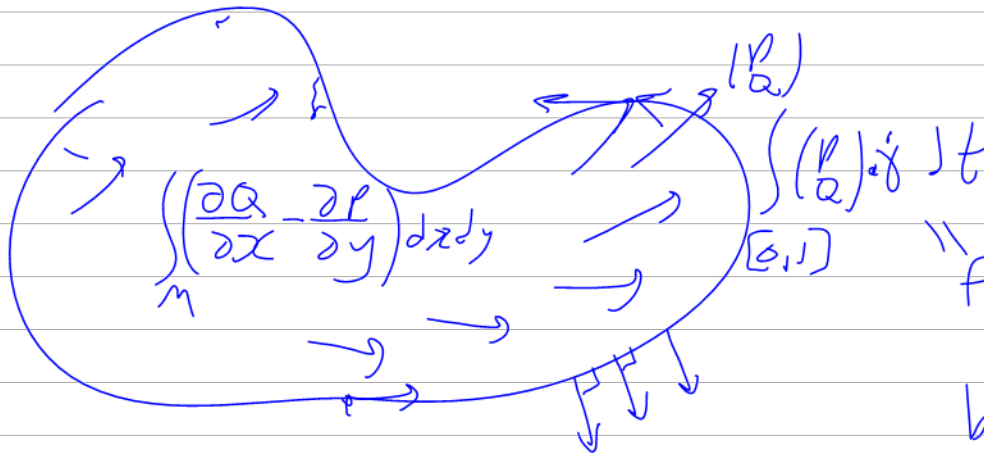
$$\boxed{\frac{\partial Q}{\partial x} - \frac{\partial P}{\partial y}} = \zeta_0$$

Rotational force

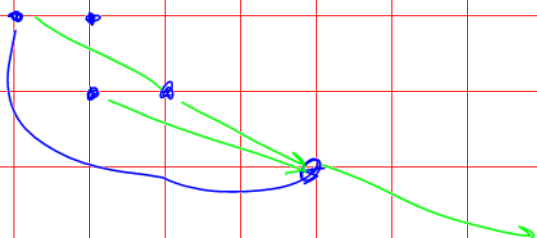
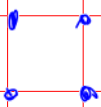
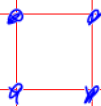
$$\vec{m} = \frac{\partial Q}{\partial x}$$

$$\vec{Q} = \frac{\partial P}{\partial y}$$

experienced by a small
cork disk floating
on fluid that flows
like (P, Q) .



"Force exerted
on a region
by the flow of
the fluid."



5

2

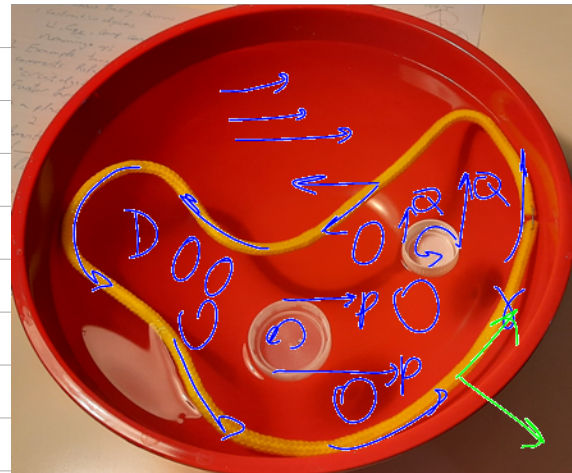
new y

A diagram showing a domain D in the complex plane. The boundary is a closed curve labeled $\gamma(t)$. A point on the boundary is labeled z_D .

$$W = p dx + q dy$$

$$dW = \left(\frac{\partial Q}{\partial x} - \frac{\partial P}{\partial y} \right) dx dy$$

If $\frac{\partial Q}{\partial x} - \frac{\partial P}{\partial y} = 1$, $\int_D \left(\frac{\partial Q}{\partial x} - \frac{\partial P}{\partial y} \right) = \int_0^T \dot{\gamma} \cdot (P) dt$
 measuring
 work.

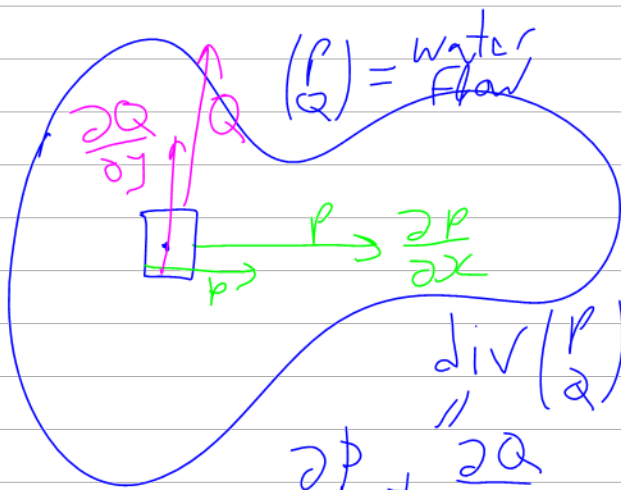


2nd interpretation $Q \rightarrow P$ $P \rightarrow \neg Q$

$$\int_D \operatorname{div}(\mathbf{r}) = \int_D \underbrace{\left(\frac{\partial p}{\partial x} + \frac{\partial Q}{\partial y} \right)}_{\operatorname{div}(\mathbf{r})} = \int_0^1 \begin{pmatrix} \dot{y}_1 \\ \dot{y}_2 \end{pmatrix} \cdot \begin{pmatrix} Q \\ p \end{pmatrix} dt = \int_0^1 \begin{pmatrix} p \\ Q \end{pmatrix} \cdot \begin{pmatrix} +\dot{y}_2 \\ -\dot{y}_1 \end{pmatrix} dt$$

$$= \int_0^1 (\rho) \cdot \vec{n} \, dt$$

↑
outgoing
normal



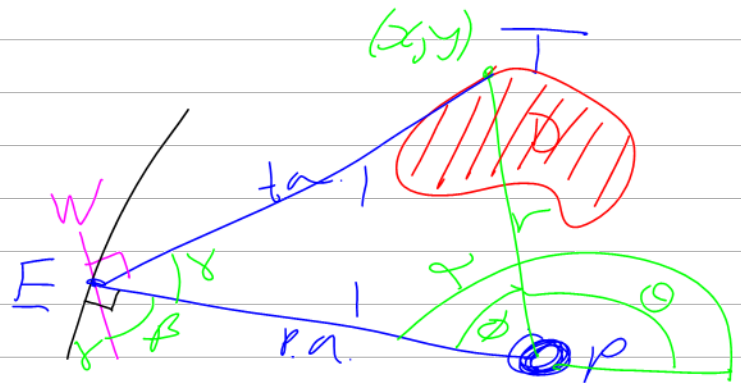
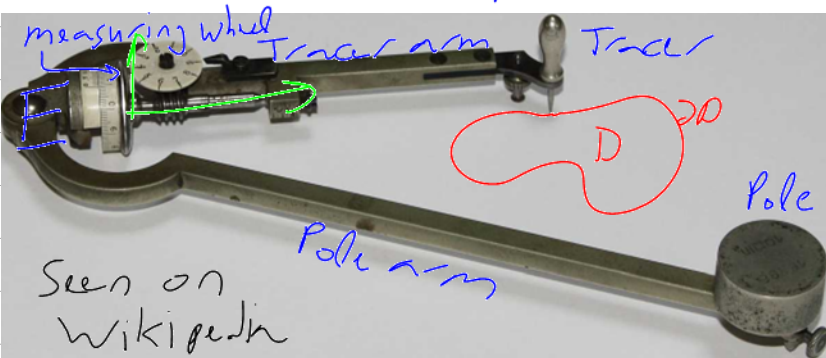
$\text{div} \begin{pmatrix} P \\ Q \end{pmatrix} = \frac{\partial P}{\partial x} + \frac{\partial Q}{\partial y}$ = how much water is inserted at every point.



4. conservation of water.

$$\begin{array}{l} \text{Amount} \\ \text{of} \\ \text{water -} \\ \text{inserted} \\ \text{over - all} \\ \text{of D} \end{array} = \begin{array}{l} \text{amount} \\ \text{of water -} \\ \text{existing} \\ \text{over -} \\ \text{of D} \end{array}$$

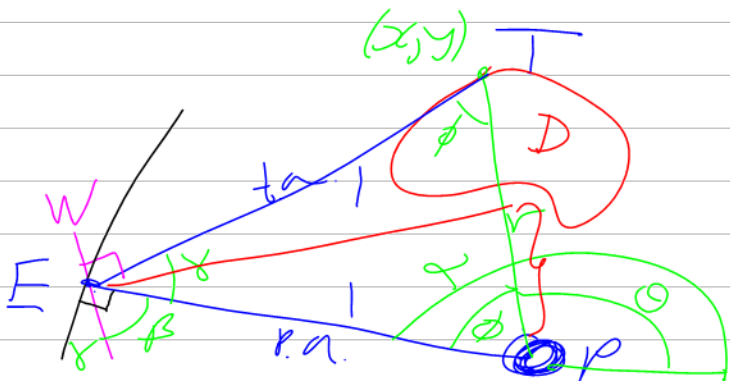
Example. The planimeter



$M = \text{configuration space of the planimeter} \subset \mathbb{R}^2_{x,y}$
 $\mathbb{R}^4_{x,y,r,\theta} \cap \mathbb{R}^2_{x,y} \subset \mathbb{R}^2_{r,\theta}$

$W: \text{infinitesimal motions} \rightarrow \text{speed of turning of measuring wheel.}$

measurement process
 $= \int W \text{ over motion.}$



$$\begin{aligned}
 x &= r \cos \theta \\
 y &= r \sin \theta \\
 dx \wedge dy &= r \cdot dr \wedge d\theta \\
 \alpha &= \theta + \phi & r &= 2 \cos \phi \\
 \gamma &= \pi - 2\phi
 \end{aligned}$$

$$\begin{aligned}
 W &= d\alpha \cdot \cos \gamma = d(\theta + \phi) \cdot \cos(\pi - 2\phi) \\
 &= -\cos(2\phi) (d\theta + d\phi)
 \end{aligned}$$

$$\begin{aligned}
 dW &= 2 \sin 2\phi d\phi \wedge d\theta & \sin 2\phi &= 2 \sin \phi \cos \phi \\
 &= \underbrace{2 \cos \phi}_r \cdot \underbrace{2 \sin \phi d\phi \wedge d\theta}_{dr} = r dr \wedge d\theta = dx \wedge dy
 \end{aligned}$$

$$\oint_{\partial D} \vec{r} \cdot d\vec{r} = \int_D dx dy = \text{Area}(D).$$

