

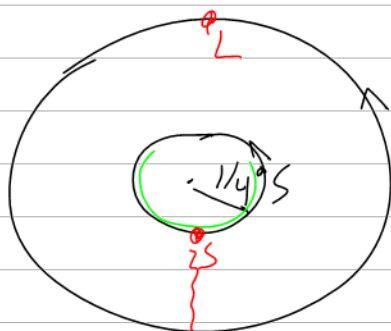
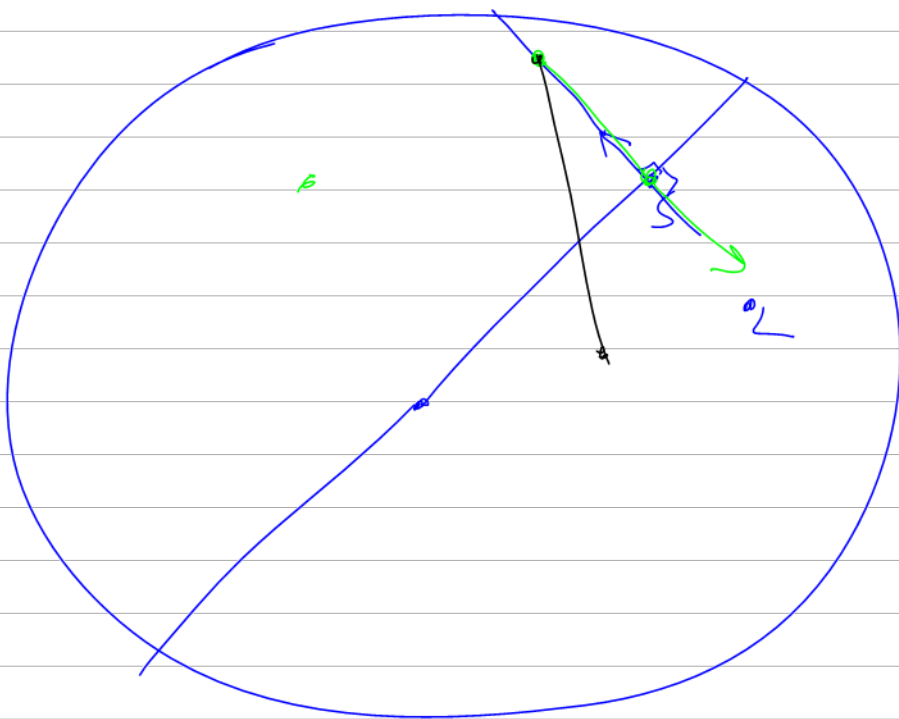
$$b_{i+1} = b_i + a_i^2$$

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

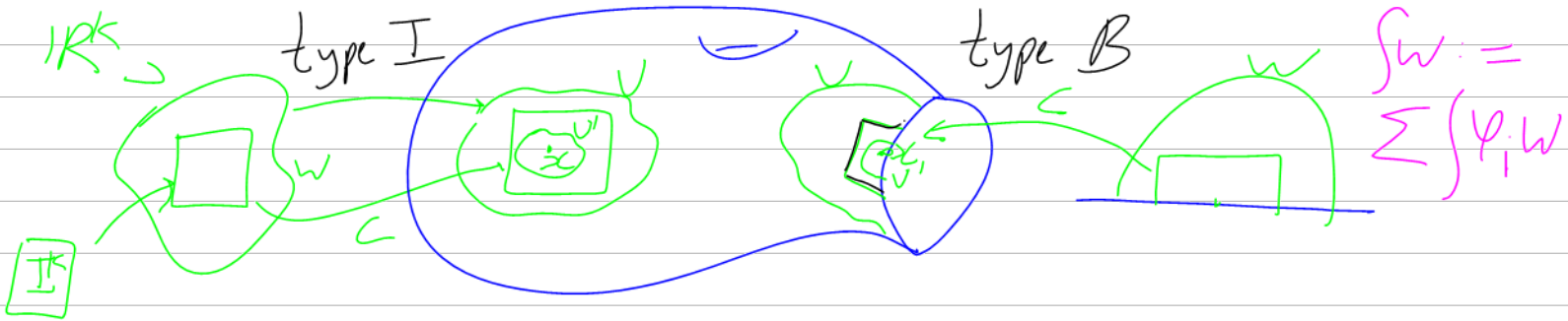
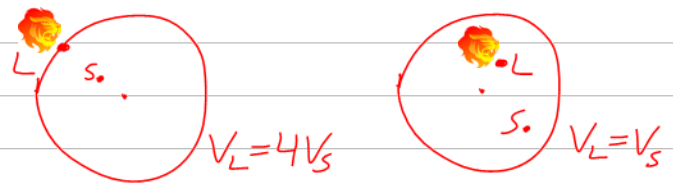
$$b_0 + \sum a_i^2 < 1$$

$$\sum a_i = \infty$$

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



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



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)

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

$$= - \int_{I^k(1,0) \cup \dots \cup (0,1)} c^* w = + \int_{\partial M} w$$

PF of thm (assembly)

$$\int_{\partial M} w = \sum_i \int_{\partial M} \psi_i w = \sum_i \int_M d(\psi_i w)$$

$$d\psi_i \wedge w + \psi_i dw$$

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

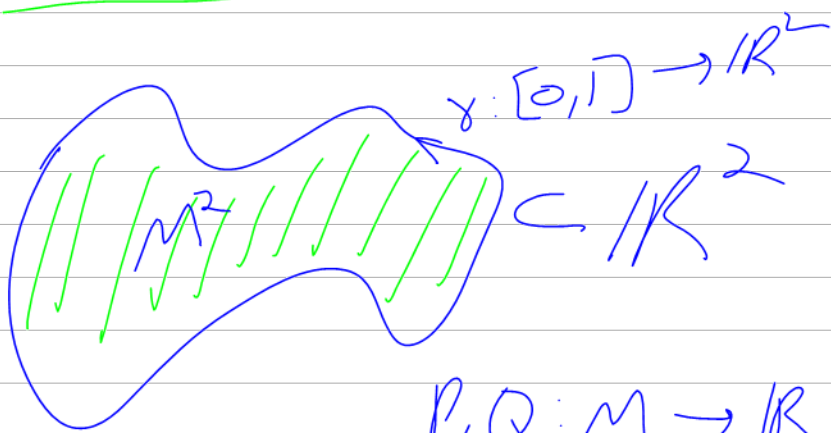
$$\int_M d(\sum_i \psi_i) \wedge \omega \quad \int_M d\omega$$

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

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

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

Fund. thm of calculus.



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

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

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

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

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

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

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

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

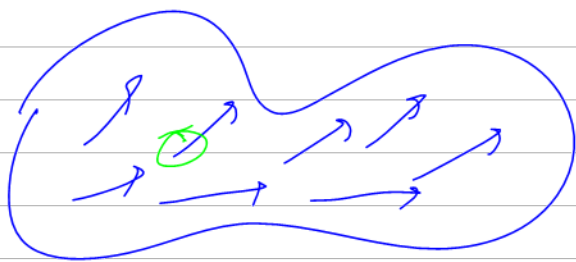
$$= \int_{[0,1]} P(x(t)) \cdot x_1'(t) dt + Q(x(t)) \cdot x_2'(t) dt$$

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

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

Two interpretations:

"curl": $\begin{pmatrix} P \\ Q \end{pmatrix}$: a vector field on M



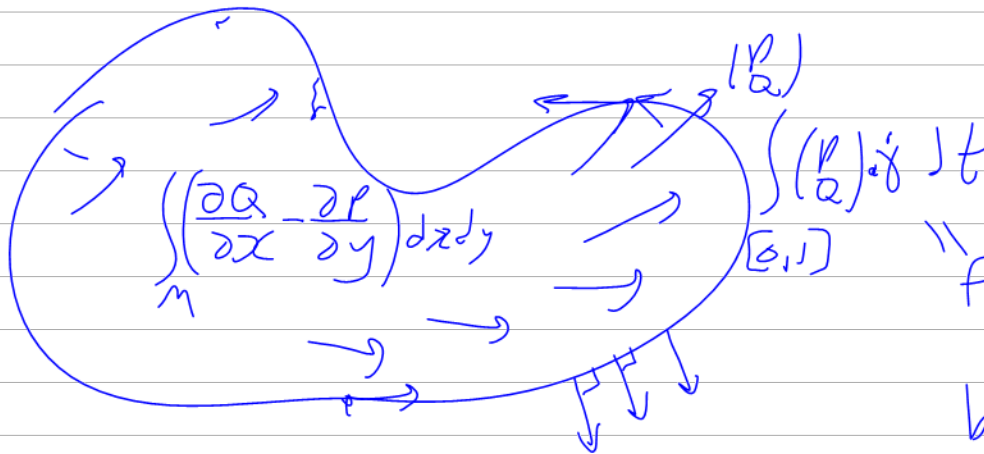
$$\boxed{\frac{\partial Q}{\partial x} - \frac{\partial P}{\partial y}} = \zeta_0$$

Rotational force

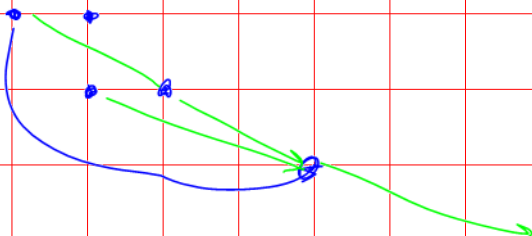
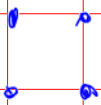
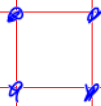
$$\rho a = \frac{\partial Q}{\partial x}$$

$$\rho b = \frac{\partial P}{\partial y}$$

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



" Force exerted on a rope δ by the flow of the fluid.

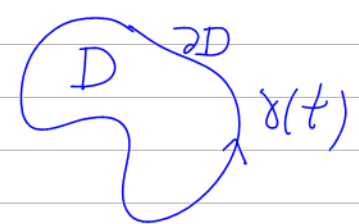


U

K

new y

Green's theorem.

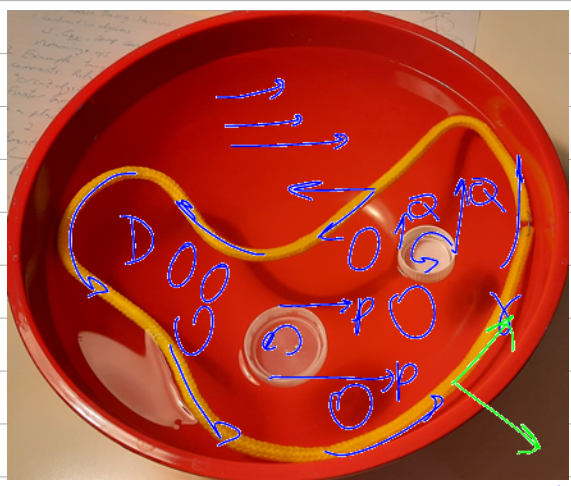


$$W = P dx + Q dy$$

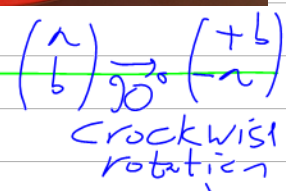
$$dW = \left(\frac{\partial Q}{\partial x} - \frac{\partial P}{\partial y} \right) dx dy$$

If $\frac{\partial Q}{\partial x} - \frac{\partial P}{\partial y} = 1$,
measuring area.

$$\int_D \left(\frac{\partial Q}{\partial x} - \frac{\partial P}{\partial y} \right) dx dy = \int_0^1 \gamma \cdot (P, Q) dt$$



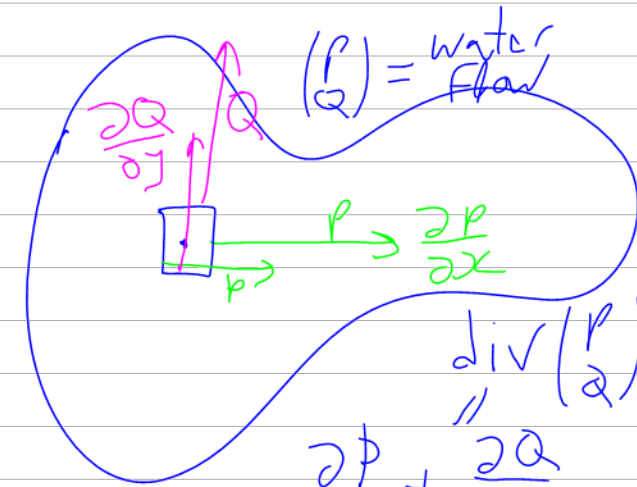
2nd interpretation $Q \rightarrow P \quad P \rightarrow -Q$



$$\int_D \text{div}(P, Q) = \int_D \left(\frac{\partial P}{\partial x} + \frac{\partial Q}{\partial y} \right) = \int_0^1 \begin{pmatrix} \dot{\gamma}_1 \\ \dot{\gamma}_2 \end{pmatrix} \cdot \begin{pmatrix} P \\ Q \end{pmatrix} dt = \int_0^1 \begin{pmatrix} P \\ Q \end{pmatrix} \cdot \begin{pmatrix} +\dot{\gamma}_2 \\ -\dot{\gamma}_1 \end{pmatrix} dt$$

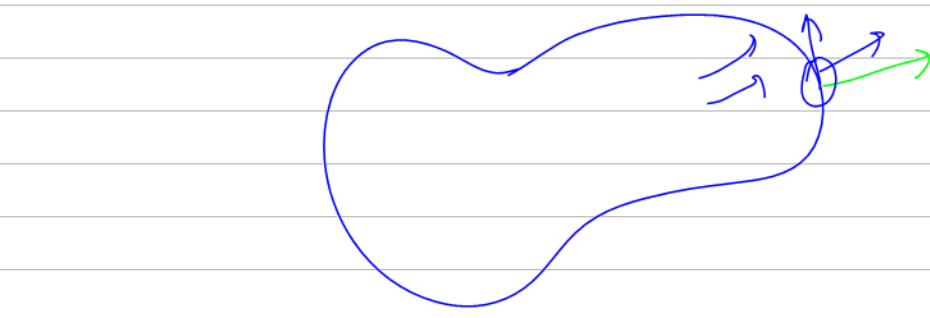
$$= \int_0^1 \begin{pmatrix} P \\ Q \end{pmatrix} \cdot \vec{n} dt$$

↑
outgoing normal



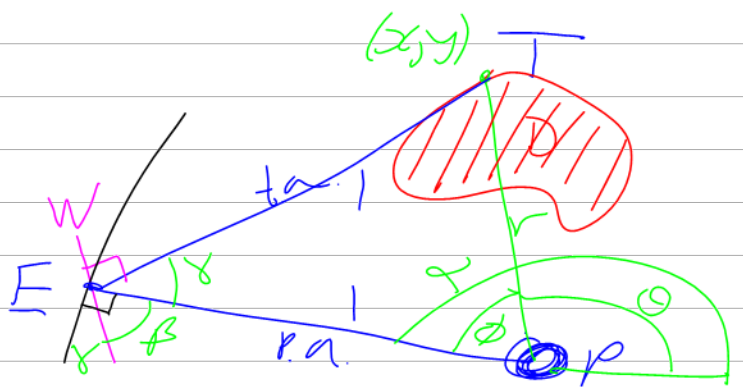
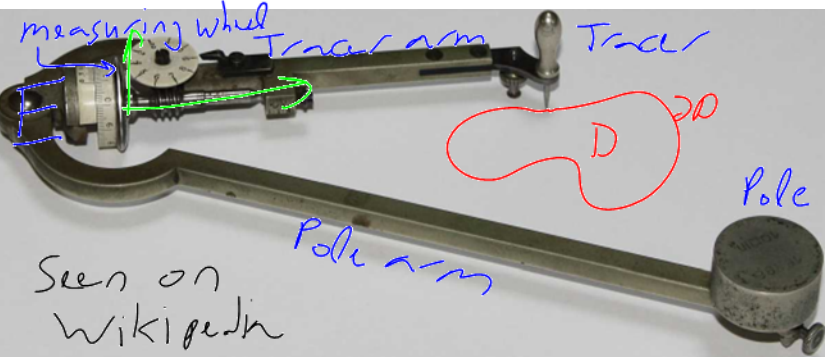
$\text{div}(P, Q) = \frac{\partial P}{\partial x} + \frac{\partial Q}{\partial y}$ = how much water is inserted at every point.

conservation of water.



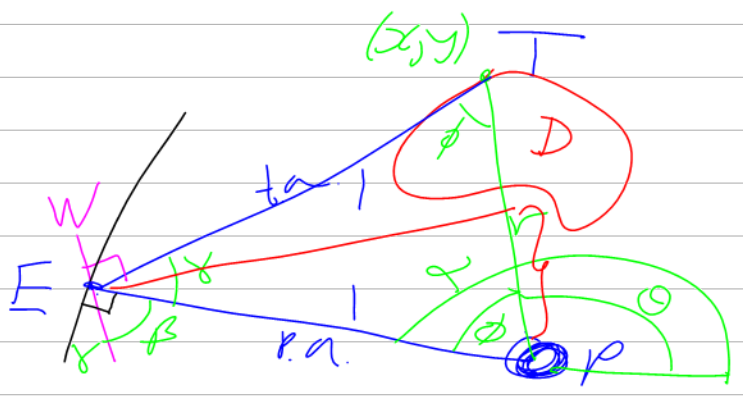
Amount of water inserted over all of D = amount of water exiting over ∂D .

Example. The planimeter



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

w : infinitesimal motions \rightarrow speed of turning of measuring wheel.
 measurement process = $\int w$ over motion.



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

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

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

$$\oint_{\partial D} \mathbf{a} \cdot \mathbf{w} = \int_D dx dy = \text{Area}(D)$$

