

**ESE 2017**

UPSC ENGINEERING SERVICES EXAMINATION

**Preliminary Examination**

**Paper  
I**

**General Studies and  
Engineering Aptitude**

**3**

**Engineering Mathematics  
and Numerical Analysis**

Comprehensive Theory *with* Practice Questions

As per new syllabus of ESE 2017



[www.madeasypublications.org](http://www.madeasypublications.org)



### **MADE EASY Publications**

Corporate Office: 44-A/4, Kalu Sarai (Near Hauz Khas Metro Station), New Delhi-110016

E-mail: [infomep@madeeasy.in](mailto:infomep@madeeasy.in)

Contact: 011-45124660, 08860378007

Visit us at: [www.madeeasypublications.org](http://www.madeeasypublications.org)

ESE-2017 : Preliminary Examination  
Paper-I : General Studies and Engineering Aptitude

### **Engineering Mathematics and Numerical Analysis**

© Copyright, by MADE EASY Publications.

All rights are reserved. No part of this publication may be reproduced, stored in or introduced into a retrieval system, or transmitted in any form or by any means (electronic, mechanical, photo-copying, recording or otherwise), without the prior written permission of the above mentioned publisher of this book.

1st Edition : 2016

MADE EASY PUBLICATIONS has taken due care in collecting the data and providing the solutions, before publishing this book. In spite of this, if any inaccuracy or printing error occurs then MADE EASY PUBLICATIONS owes no responsibility. MADE EASY PUBLICATIONS will be grateful if you could point out any such error. Your suggestions will be appreciated.

© All rights reserved by MADE EASY PUBLICATIONS. No part of this book may be reproduced or utilized in any form without the written permission from the publisher.

# Preface

The compilation of this book **Engineering Mathematics and Numerical Analysis** was motivated by the desire to provide a concise book which can benefit students to understand the concepts of engineering mathematics topics.



**B. Singh** (Ex. IES)

This textbook **Engineering Mathematics and Numerical Analysis** provides all the requirements of the students, i.e. comprehensive coverage of theory, fundamental concepts and objective type questions articulated in a lucid language. The concise presentation will help the readers grasp the theory of this subject with clarity and apply them with ease to solve objective questions quickly. This book not only covers the syllabus of ESE but also addresses the need of many other competitive examinations. Topics like 'Linear Algebra, Calculus, Differential Equations, Complex Functions, Probability & Statistics, Numerical Method and Transform Theory' are given full emphasis, keeping in mind of our research on their importance in competitive examinations.

We have put in our sincere efforts to present detailed theory and MCQs without compromising the accuracy of answers. For the interest of the readers, some notes, do you know and interesting facts are given in the comprehensive manner. At the end of each chapter, sets of practice question are given with their keys, that will allow the readers to evaluate their understanding of the topics and sharper their question solving skills.

Our team has made their best efforts to remove all possible errors of any kind. Nonetheless, we would highly appreciate and acknowledge if you find and share with us any printing and conceptual errors.

It is impossible to thank all the individuals who helped us, but we would like to sincerely thank all the authors, editors and reviewers for putting in their efforts to publish this book.

With Best Wishes

**B. Singh**

CMD, MADE EASY

## Engineering Mathematics and Numerical Analysis

### Chapter 1

#### Linear Algebra ..... 1

1.1	Introduction .....	1
1.2	Algebra of Matrices.....	1
1.2.1	Definition of Matrix.....	1
1.2.2	Special Types of Matrices .....	1
1.2.3	Equality of Two Matrices .....	4
1.2.4	Addition of Matrices.....	4
1.2.5	Substraction of Two Matrices .....	5
1.2.6	Multiplication of a Matrix by a Scalar ....	5
1.2.7	Multiplication of Two Matrices.....	5
1.2.8	Trace of a Matrix.....	6
1.2.9	Transpose of a Matrix .....	6
1.2.10	Conjugate of a Matrix .....	6
1.2.11	Transposed Conjugate of Matrix .....	7
1.2.12	Classification of Real Matrices .....	7
1.2.13	Classification of Complex Matrices.....	8
1.3	Determinants.....	9
1.3.1	Definition .....	9
1.3.2	Minors, Cofactors and Adjoint.....	9
1.3.3	Cofactors .....	9
1.3.4	Adjoint.....	10
1.3.5	Determinant of order n.....	10
1.3.6	Properties of Determinants .....	10
1.4	Inverse of Matrix.....	12
1.4.1	Adjoint of a Square Matrix .....	12
1.4.2	Properties of Inverse .....	12
1.5	Rank of A Matrix.....	12
1.5.1	Elementary Matrices .....	13
1.5.2	Results.....	13
1.6	Sub-Spaces : Basis and Dimension.....	13
1.6.1	Introduction .....	13
1.6.2	Vector .....	13

1.6.3	Linearly dependent and Linearly Independent Sets of Vectors.....	14
1.6.4	Some properties of linearly Independent and Dependent Sets of Vectors .....	14
1.6.5	Subspaces of an N-vector space $V_n$ .....	15
1.6.6	Row and column spaces of a matrix. Row and column ranks of a Matrix .....	16
1.6.7	Orthogonality of Vectors .....	17
1.7	System of Equations.....	18
1.7.1	Homogenous Linear Equations .....	18
1.7.2	System of Linear Non-Homogeneous Equations .....	19
1.7.3	Homogenous Polynomial .....	21
1.8	Eigenvalues and Eigenvectors.....	21
1.8.1	Definitions .....	21
1.8.2	Some Results Regarding Characteristic Roots and Characteristic Vectors.....	22
1.8.3	Process of Finding the Eigenvalues and Eigenvectors of a Matrix .....	22
1.8.4	Properties of Eigen Values .....	22
1.8.5	The Cayley-Hamilton Theorem.....	23
1.8.6	Similar Matrices.....	25
1.8.7	Diagonalisation of a Matrix.....	25
	<i>Illustrative Examples</i> .....	26
	<i>Objective Brain Teasers</i> .....	28

### Chapter 2

#### Calculus ..... 30

2.1	Limit .....	30
2.1.1	Definition .....	30
2.1.2	Right and Left Hand Limits .....	30
2.1.3	Various Formulae .....	30
2.1.4	Some Useful Results.....	31
2.1.5	Indeterminate Forms .....	31

2.2	Continuity .....	32	2.6.5	Slope Determination of Line.....	58
2.2.1	Definition .....	32	2.7	Partial Derivatives .....	58
2.2.2	Continuity from Left and Continuity from Right.....	33	2.7.1	Definition of Partial Derivative .....	58
2.2.3	Continuity in an Open Interval.....	33	2.7.2	Second order partial differential coefficients .....	58
2.2.4	Continuity in a Closed Interval.....	33	2.7.3	Homogenous Functions .....	59
2.3	Differentiability .....	33	2.7.4	Euler's Theorem on homogenous functions .....	59
2.3.1	Progressive and Regressive Derivatives..	33	2.8	Total Derivatives .....	60
2.3.2	Differentiability in an Open Interval.....	33	2.9	Maxima and Minima (of Function of Two Independent Variables).....	60
2.3.3	Differentiability in a Closed Interval.....	34	2.9.1	Definitions .....	60
2.3.4	Relationship between Differentiability and Continuity .....	34	2.9.2	Necessary Conditions .....	60
2.4	Mean Value Theorems .....	34	2.9.3	Sufficient Condition for Maxima or Minima .....	60
2.4.1	Rolle's Theorem .....	34	2.10	Theorems of Integral Calculus.....	61
2.4.2	Geometrical Interpretation.....	34	2.10.1	Fundamental Formulae.....	61
2.4.3	Lagrange's Mean Value Theorem.....	37	2.10.2	Useful Trigonometric Identities.....	61
2.4.4	Geometrical Interpretation.....	37	2.10.3	Methods of Integration.....	62
2.4.5	Some applications of Lagrange's Mean Value theorem.....	40	2.11	Definite Integrals.....	66
2.4.6	Some Important Deductions from Mean Value Theorems .....	41	2.11.1	Fundamental Properties of Definite Integrals.....	66
2.4.7	Some Standard Results on Continuity and Differentiability of Commonly used Functions.....	41	2.12	Applications of Integration.....	71
2.5	Computing the Derivative .....	41	2.12.1	Preliminary : Curve Tracing .....	71
2.5.1	Differentiation by Substitution .....	42	2.12.2	Areas of Cartesian Curves.....	74
2.5.2	Implicit Differentiation.....	44	2.12.3	Areas of Polar Curves .....	76
2.5.3	Logarithmic Differentiation.....	46	2.12.4	Derivative of arc Length d.....	76
2.5.4	Derivatives of Functions in Parametric forms.....	47	2.12.5	Lengths of Curves .....	77
2.6	Applications of Derivatives.....	48	2.12.6	Volumes of Revolution .....	78
2.6.1	Increasing and Decreasing Functions .....	48	2.13	Multiple Integrals and Their Applications .....	79
2.6.2	Relative or Local Maxima and Minima (of function of a single independent variable).....	52	2.13.1	Double Integrals .....	80
2.6.3	Working Rules for Finding (Absolute) Maximum and Minimum in Range [a, b] ..	53	2.13.2	Change of order of Integration .....	81
2.6.4	Taylor's and Maclaurin's Series Expansion of Functions.....	55	2.13.3	Double Integrals in Polar Co-ordinates..	83
			2.13.4	Area Enclosed by Plane Curves .....	83
			2.13.5	Triple Integrals.....	84
			2.14	Vectors .....	85
			2.14.1	Introduction .....	85
			2.14.2	Basic Definitions .....	86
			2.14.3	Equality of Vectors .....	86
			2.14.4	Components of a Vector .....	86

2.14.5	Position Vector .....	87
2.14.6	Vector Addition, Scalar Multiplication.....	87
2.14.7	Unit Vectors .....	89
2.14.8	Length and Direction of Vectors.....	89
2.14.9	Inner Product (Dot Product).....	91
2.14.10	Vector Product (Cross Product).....	93
2.14.11	Scalar Triple Product .....	96
2.14.12	Vector Triple Product .....	98
2.14.13	Vector and Scalar Functions and Fields. Derivatives .....	98
2.14.14	Gradient of a Scalar Field .....	101
2.14.15	Directional Derivative.....	102
2.14.16	Gradient Characterizes Maximum Increase.....	102
2.14.17	Vector Fields that are Gradients of a Scalar Field (“Potential”).....	104
2.14.18	Divergence of a Vector Field .....	104
2.14.19	Curl of a Vector Field .....	106
2.14.20	Vector Integral Calculus: Integral Theorems .....	109
2.14.21	Green’s Theorem in the Plane .....	116
2.14.22	Triple Integrals : Divergence Theorem of Gauss .....	117
	<i>Illustrative Examples</i> .....	120
	<i>Objective Brain Teasers</i> .....	122

### Chapter 3 Differential Equations ..... 124

3.1	Introduction .....	124
3.2	Differential Equations of First Order.....	124
3.2.1	Definitions .....	124
3.2.2	Solution of a Differential Equation.....	125
3.2.3	Equations of the First Order and First Degree.....	125
3.2.4	Orthogonal Trajectories.....	131
3.3	Linear Differential Equations (Of nth Order)...	135
3.3.1	Definitions .....	135
3.3.2	Rules for Finding The Complementary Function.....	136
3.3.3	Inverse Operator.....	137

3.3.4	Rules For Finding The Particular Integral ..	138
3.3.5	Summary: Working Procedure to Solve the Equation.....	143
3.4	Two Other Methods of Finding PI.....	145
3.4.1	Method of Variation of Parameters....	145
3.5	Equations Reducible to Linear Equation with Constant Coefficient.....	146
	<i>Illustrative Examples</i> .....	147
	<i>Objective Brain Teasers</i> .....	148

### Chapter 4 Complex Functions ..... 150

4.1	Introduction .....	150
4.2	Complex Functions.....	150
4.2.1	Exponential Function of a Complex Variable .....	150
4.2.2	Circular Function of a Complex Variable..	151
4.2.3	Hyperbolic Functions.....	151
4.2.4	Inverse Hyperbolic Functions .....	152
4.3	Limit of a complex function .....	153
4.4	Singularity.....	153
4.4.1	Isolated Singular Point .....	153
4.4.2	Essential Singularity .....	154
4.4.3	Removable Singularity .....	154
4.4.4	Steps to Find Singularity.....	154
4.5	Derivative of $f(z)$ .....	154
4.6	Analytic Functions .....	155
4.6.1	Analytic Functions .....	155
4.6.2	Harmonic Functions.....	156
4.6.3	Orthogonal Curves .....	157
4.7	Complex Integration .....	157
4.7.1	Line integral in the complex plane ....	157
4.7.2	Definition of the Complex Line Integral ...	158
4.7.3	First Method: Indefinite Integration and Substitution of Limits .....	158
4.7.4	Second Method: Use of a Representation of the Path.....	159
4.8	Cauchy’s Theorem .....	161
4.9	Cauchy’s Integral Formula.....	162
4.10	Series of Complex Terms.....	163

4.11	Zeros and Singularities or Poles of an Analytic Function.....	164
4.11.1	Zeros of an Analytic Function.....	164
4.12	Residues.....	165
4.12.1	Residue Theorem.....	165
4.12.2	Calculation of Residues.....	166
	<i>Illustrative Examples</i> .....	167
	<i>Objective Brain Teasers</i> .....	168

## Chapter 5

### Probability & Statistics..... 169

5.1	Probability Fundamentals.....	169
5.1.1	Definitions.....	169
5.1.2	Types of Events.....	170
5.1.3	DeMorgan's Law.....	170
5.1.4	Approaches to Probability.....	171
5.1.5	Axioms of Probability.....	171
5.1.6	Rules of Probability.....	172
5.2	Statistics.....	174
5.2.1	Introduction.....	174
5.2.2	Arithmetic Mean.....	174
5.2.3	Median.....	175
5.2.4	Mode.....	176
5.2.5	Properties Relating Mean, Median and Mode.....	177
5.2.6	Standard Deviation.....	178
5.2.7	Coefficient of Variation.....	180
5.3	Probability Distributions.....	180
5.3.1	Random Variables.....	180
5.3.2	Distributions.....	181
5.3.3	Types of Distributions.....	181
5.2.1	Introduction.....	174
5.2.2	Arithmetic Mean.....	174
5.2.3	Median.....	175
5.2.4	Mode.....	176
5.2.5	Properties Relating Mean, Median and Mode.....	177
5.2.6	Standard Deviation.....	178
5.2.7	Variance.....	179
5.2.8	Coefficient of Variation.....	180

5.3	Probability Distributions.....	180
5.3.1	Random Variables.....	180
5.3.2	Distributions.....	181
5.3.3	Types of Distributions.....	181
	<i>Illustrative Examples</i> .....	192
	<i>Objective Brain Teasers</i> .....	193

## Chapter 6

### Numerical Method..... 195

6.1	Introduction.....	195
6.1.1	Analytical Methods.....	195
6.1.2	Numerical Methods.....	195
6.1.3	Errors in Numerical Methods.....	196
6.2	Numerical Solution of System of Linear Equations.....	197
6.2.1	Method of Factorisation or Triangularisation Method (Dolittle's Triangularisation Method).....	197
6.2.2	Gauss Seidel Method.....	200
6.3	Numerical Solutions of Nonlinear Algebraic and Trans-cendental Equations by Bisection, Regula Falsi, Secant and Newton-Raphson Methods.....	201
6.3.1	Roots of Algebraic Equations.....	201
6.3.2	Descartes's Rule of Signs.....	203
6.3.3	Numerical Methods for Root Finding.....	203
6.4	Numerical Integration (Quadrature) by Trapezoidal and Simpson's Rules.....	207
6.4.1	Trapezoidal Rule.....	207
6.4.2	Simpson's Rules.....	208
6.4.3	Truncation Error Formulae for Trapezoidal and Simpson's Rule.....	211
6.5	Numerical Solution of Ordinary Differential Equations.....	212
6.5.1	Introduction.....	212
6.5.2	Euler's Method.....	212
6.5.3	Modified Euler's Method.....	214
6.5.4	Runge-Kutta Method.....	215
6.5.5	Stability Analysis.....	216
	<i>Illustrative Examples</i> .....	216
	<i>Objective Brain Teasers</i> .....	218

## Chapter 7

### Transform Theory ..... 219

7.1	Laplace Transform .....	219
7.2	Definition .....	219
7.3	Transforms of Elementary Functions .....	220
7.4	Properties of Laplace Transforms .....	220
7.4.1	Linearity Property .....	220
7.4.2	First Shifting Property.....	220
7.4.3	Change of Scale Property.....	221
7.4.4	Existence Conditions.....	221
7.4.5	Transforms of Derivatives.....	221
7.4.6	Transforms of Integrals.....	223
7.4.7	Multiplication By $t^n$ .....	223
7.4.8	Division By $t$ .....	223

7.5	Evaluation of Integrals by Laplace Transforms.....	223
7.6	Inverse Transforms – Method of Partial Fractions .....	225
7.7	Unit Step Function .....	226
7.7.1	Transform of Unit Function.....	226
7.8	Second Shifting Property .....	226
7.9	Unit Impulse Function .....	226
7.9.1	Transform of Unit Impulse Function .....	227
7.10	Periodic functions .....	227
7.11	Fourier Transform .....	227
7.12	Dirichlet's Conditions.....	228
7.12.1	Fourier Cosine and Sine Series .....	228
7.12.2	The Cosine and Sine Series Extensions.....	230
	<i>Illustrative Examples</i> .....	231
	<i>Objective Brain Teasers</i> .....	232





## 2.1 Limit

### 2.1.1 Definition

A number  $A$  is said to be limit of a function  $f(x)$  at  $x = a$  if for any arbitrarily chosen positive integer  $\epsilon$ , however small but not zero there exist a corresponding number  $\delta$  greater than zero such that:  $|f(x) - A| < \epsilon$  for all values of  $x$  for which  $0 < |x - a| < \delta$  where  $|x - a|$  means the absolute value of  $(x - a)$  without any regard to sign.

### 2.1.2 Right and Left Hand Limits

If  $x$  approaches  $a$  from the right, that is, from larger value of  $x$  than  $a$ , the limit of  $f$  as defined before is called the right hand limit of  $f(x)$  and is written as:

$$\lim_{x \rightarrow a+0} f(x) \text{ or } f(a+0) \text{ or } \lim_{x \rightarrow a^+} f(x)$$

Working rule for finding right hand limit is, put  $a + h$  for  $x$  in  $f(x)$  and make  $h$  approach zero.

In short, we have, 
$$f(a+0) = \lim_{h \rightarrow 0} f(a+h)$$

Similarly if  $x$  approaches  $a$  from left, that is from smaller values of  $x$  than  $a$ , the limit of  $f$  is called the left hand limit and is written as:

$$\lim_{x \rightarrow a-0} f(x) \text{ or } f(a-0) \text{ or } \lim_{x \rightarrow a^-} f(x)$$

In this case, we have, 
$$f(a-0) = \lim_{h \rightarrow 0} f(a-h)$$

If both right hand and left hand limit of  $f$ , as  $x \rightarrow a$  exist and are equal in value, their common value, evidently, will be the limit of  $f$  as  $x \rightarrow a$ . If however, either or both of these limits do not exist, the limit of  $f$  as  $x \rightarrow a$  does not exist. Even if both these limits exist but are not equal in value then also the limit of  $f$  as  $x \rightarrow a$  does not exist.

$\therefore$  when 
$$\lim_{x \rightarrow a^+} f(x) = \lim_{x \rightarrow a^-} f(x)$$

then 
$$\lim_{x \rightarrow a} f(x) = \lim_{x \rightarrow a^+} f(x) = \lim_{x \rightarrow a^-} f(x)$$

Limit of a function can be any real number,  $\infty$  or  $-\infty$ . It can sometimes be  $\infty$  or  $-\infty$ , which are also allowed values for limit of a function.

### 2.1.3 Various Formulae

These formulae are sometimes useful while taking limits.

$$(1+x)^n = 1 + nx + \frac{n(n-1)}{2!}x^2 + \frac{n(n-1)(n-2)}{3!}x^3 + \dots$$

$$(1-x)^{-1} = 1 + x + x^2 + x^3 + \dots$$

$$a^x = 1 + x \log a + \frac{x^2}{2!} (\log a)^2 + \frac{x^3}{3!} (\log a)^3 + \dots$$

$$e^x = 1 + x + \frac{x^2}{2!} + \frac{x^3}{3!} + \dots$$

$$\sin x = x - \frac{x^3}{3!} + \frac{x^5}{5!} - \dots$$

$$\cos x = 1 - \frac{x^2}{2!} + \frac{x^4}{4!} - \dots$$

$$\tan x = x + \frac{x^3}{3} + \frac{2}{15}x^5 + \dots$$

$$\log(1+x) = x - \frac{x^2}{2} + \frac{x^3}{3} - \frac{x^4}{4} + \dots \quad |x| < 1$$

$$\log(1-x) = -\left(x + \frac{x^2}{2} + \frac{x^3}{3} + \frac{x^4}{4} + \dots\right) \quad |x| < 1$$

$$\sin^{-1} x = x + \frac{x^3}{6} + \frac{3x^5}{40} + \dots$$

$$\tan^{-1} x = x - \frac{x^3}{3} + \frac{x^5}{5} - \dots$$

$$\sin hx = x + \frac{x^3}{3!} + \frac{x^5}{5!} + \dots$$

$$\cos hx = 1 + \frac{x^2}{2!} + \frac{x^4}{4!} + \dots$$

**Remember:**  $\log 1 = 0$ ;  $\log e = 1$ ;  $\log \infty = \infty$ ;  $\log 0 = -\infty$

### 2.1.4 Some Useful Results

1.  $\lim_{x \rightarrow 0} \frac{\sin x}{x} = 1$
2.  $\lim_{x \rightarrow 0} \cos x = 1$
3.  $\lim_{x \rightarrow 0} \frac{\tan x}{x} = 1$
4.  $\lim_{x \rightarrow 0} (1+x)^{\frac{1}{x}} = e$
5.  $\lim_{x \rightarrow 0} (1+nx)^{\frac{1}{x}} = e^n$
6.  $\lim_{x \rightarrow \infty} \left(1 + \frac{1}{x}\right)^x = e$
7.  $\lim_{x \rightarrow \infty} \left(1 + \frac{a}{x}\right)^x = e^a$

### 2.1.5 Indeterminate Forms

A fraction whose numerator and denominator both tend to zero as  $x \rightarrow a$  is an example of an indeterminate form written as  $0/0$ . It has no definite values. Other indeterminate forms are:  $\infty/\infty$ ,  $\infty - \infty$ ,  $0 \times \infty$ ,  $1^\infty$ ,  $0^0$ ,  $\infty^0$ . (Indeterminate forms are not any definite number and hence are not acceptable as limits. To find limit in such cases, we use the L'Hospital's rule)

#### 2.1.5.1 Indeterminate Form-I $\left(\frac{0}{0} \text{ or } \frac{\infty}{\infty}\right)$

Use L'Hospital's Rule.

**L'Hospital Rule:** If  $f(x)$  and  $\phi(x)$  be two functions of  $x$  and if,

$$\lim_{x \rightarrow a} f(x) = 0 \quad \text{and} \quad \lim_{x \rightarrow a} \phi(x) = 0$$

or if  $\lim_{x \rightarrow a} f(x) = \infty$  and  $\lim_{x \rightarrow a} \phi(x) = \infty$ ,

then 
$$\lim_{x \rightarrow a} \frac{f(x)}{\phi(x)} = \lim_{x \rightarrow a} \frac{f'(x)}{\phi'(x)}$$

provided, the latter limit exists, finite or infinite.

**Working Rule:** If the limit of  $f(x)/\phi(x)$  as  $x \rightarrow a$  takes the form  $0/0$ , differentiate the numerator and denominator separately with respect to  $x$  and obtain a new function  $f'(x)/\phi'(x)$ . Now as  $x \rightarrow a$  if it again takes the form  $0/0$ , differentiate the numerator and denominator again with respect to  $x$  and repeat the above process, until the indeterminate form is removed and we get either a real number,  $\infty$  or  $-\infty$  as a limit.

**Caution:** Before applying L'Hospital's rule at any stage, be sure that the form is  $0/0$ . Do not go on applying this rule, if the form is not  $0/0$ .

### 2.1.5.2 Indeterminate Form-II ( $0 \times \infty$ )

This form can be easily reduced to the form  $0/0$  or to the form  $\infty/\infty$ , and then L'Hospital's rule may be applied.

$$\text{Let } \lim_{x \rightarrow a} f(x) = 0 \quad \text{and} \quad \lim_{x \rightarrow a} \phi(x) = \infty.$$

Then we can write

$$\lim_{x \rightarrow a} f(x) \cdot \phi(x) = \lim_{x \rightarrow a} \frac{f(x)}{1/\phi(x)} \quad [\text{form } 0/0] \quad \text{or} \quad \lim_{x \rightarrow a} \frac{\phi(x)}{1/f(x)} \quad [\text{form } \infty/\infty]$$

Thus  $\lim_{x \rightarrow a} f(x) \cdot \phi(x)$  is reduced to the form  $0/0$  or  $\infty/\infty$  which can now be evaluated by L'Hospital rule.

### 2.1.5.3 Indeterminate Form-III ( $0^0$ or $1^\infty$ or $\infty^0$ )

Suppose  $\lim_{x \rightarrow a} [f(x)]^{\phi(x)}$  takes any one of these three forms.

Then let  $y = \lim_{x \rightarrow a} [f(x)]^{\phi(x)}$

Taking log on both sides, we get

$$\log y = \lim_{x \rightarrow a} \phi(x) \cdot \log f(x).$$

Now in any of these above cases  $\log y$  takes the form  $0 \times \infty$  which is changed to the form  $0/0$  or  $\infty/\infty$  then it can be evaluated by previous methods.

## 2.2 Continuity

### 2.2.1 Definition

A function  $f(x)$  is defined for  $x = a$  is said to be continuous at  $x = a$  if:

1.  $f(a)$  i.e., the value of  $f(x)$  at  $x = a$  is a definite number and
2. the limit of the function  $f(x)$  as  $x \rightarrow a$  exists and is equal to the value of  $f(x)$  at  $x = a$ .

**Note:** On comparing the definitions of limit and continuity we find that a function  $f(x)$  is continuous at  $x = a$  if

$$\lim_{x \rightarrow a} f(x) = f(a)$$

Thus  $f(x)$  is continuous at  $x = a$  if we have  $f(a + 0) = f(a - 0) = f(a)$ , otherwise it is discontinuous at  $x = a$ .

### 2.2.2 Continuity from Left and Continuity from Right

Let  $f$  be a function defined on an open interval  $I$  and let  $a$  be any point in  $I$ . We say that  $f$  is continuous from the left at  $a$ , if  $\lim_{x \rightarrow a-0} f(x)$  exists and is equal to  $f(a)$ . Similarly  $f$  is said to be continuous from the right at  $a$ , if

$\lim_{x \rightarrow a+0} f(x)$  exists and is equal to  $f(a)$ .

$\therefore$  A function  $f(x)$  is continuous at  $x = a$ , if it is continuous from left as well as continuous from right.

### 2.2.3 Continuity in an Open Interval

A function  $f$  is said to be continuous in open interval  $(a, b)$ , if it is continuous at each point of open interval.

### 2.2.4 Continuity in a Closed Interval

Let  $f$  be a function defined on the closed interval  $(a, b)$   $f$  is said to be continuous on the closed interval  $[a, b]$  if it is:

1. continuous from the right at  $a$  and
2. continuous from the left at  $b$  and
3. continuous on the open interval  $(a, b)$ .

## 2.3 Differentiability

Derivative at  $a$  point: Let  $I$  denote the open interval  $(a, b)$  in  $R$  and let  $x_0 \in I$ . Then a function  $f: I \rightarrow R$  is said to be differentiable at  $x_0$ , if:

$$\lim_{h \rightarrow 0} \left[ \frac{f(x_0 + h) - f(x_0)}{h} \right] \text{ or } \lim_{x \rightarrow x_0} \left[ \frac{f(x) - f(x_0)}{x - x_0} \right]$$

exist (**finitely**) and is denoted by  $f'(x_0)$ .

### 2.3.1 Progressive and Regressive Derivatives

The progressive derivative of  $f$  (or right derivative of  $f$ ) at  $x = x_0$  is given by

$$\lim_{h \rightarrow 0} \frac{f(x_0 + h) - f(x_0)}{h}, \quad h > 0 \text{ and is denoted by } Rf'(x_0) \text{ or by } f'(x_0 + 0) \text{ or by } f'(x_0^+).$$

The regressive derivative of  $f$  (or left derivative of  $f$ ) at  $x = x_0$  is given by

$$\lim_{h \rightarrow 0} \frac{f(x_0 - h) - f(x_0)}{-h}, \quad h > 0 \text{ and is denoted by } Lf'(x_0) \text{ or by } f'(x_0 - 0) \text{ or by } f'(x_0^-).$$

### 2.3.2 Differentiability in an Open Interval

A function  $f$  is said to be differentiable in an open interval  $(a, b)$ , if it is differentiable at each point of the open interval.

### 2.3.3 Differentiability in a Closed Interval

A function  $f: [a, b] \rightarrow R$  is said to be differentiable in closed interval  $[a, b]$  if it is

1. differentiable from right at  $a$  [i.e.  $R f'(a)$  exists] **and**
2. differentiable from left at  $b$  [i.e.  $L f'(a)$  exists] **and**
3. differentiable in the open interval  $(a, b)$ .

### 2.3.4 Relationship between Differentiability and Continuity

**Theorem:** If a function is differentiable at any point, then it is necessarily continuous at that point, proof of this theorem follows from definitions of differentiability and continuity.

**Note:** The converse of this theorem not true.

i.e. Continuity is a necessary but not a sufficient condition for the existence of a finite derivative (differentiability).

i.e. differentiability  $\Rightarrow$  continuity

But continuity  $\not\Rightarrow$  differentiability

## 2.4 Mean Value Theorems

### 2.4.1 Rolle's Theorem

If a function  $f(x)$  is such that:

1.  $f(x)$  is continuous in the closed interval  $a \leq x \leq b$  **and**
2.  $f'(x)$  exists for every point in the open interval  $a < x < b$  **and**
3.  $f(a) = f(b)$ ,

then there exists at least one value of  $x$ , say  $c$  where  $a < c < b$  such that  $f'(c) = 0$ .

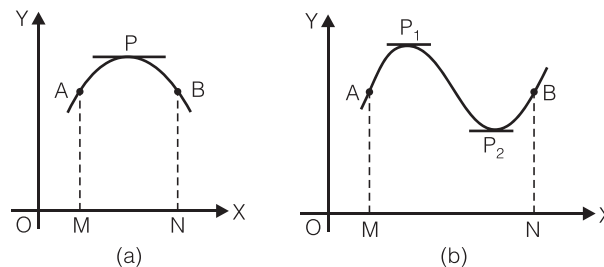
**Note:** Rolle's theorem will not hold good.

1. If  $f(x)$  is discontinuous at some point in the interval  $a < x < b$
2. If  $f'(x)$  does not exist at some point in the interval  $a < x < b$  or
3. If  $f(a) \neq f(b)$

### 2.4.2 Geometrical Interpretation

Let  $A, B$  be the points on the curve  $y = f(x)$  corresponding to the real numbers  $a, b$ , respectively.

Since  $f(x)$  is continuous in  $[a, b]$ , the curve  $y = f(x)$  has a tangent at each point between  $A$  and  $B$ . Also as  $f(a) = f(b)$  the ordinates of the points  $A$  and  $B$  are equal i.e.  $MA = NB$  [See Figure (a)].



Then Rolle's theorem asserts that there is atleast one point lying between  $A$  and  $B$  such that the tangent at which is parallel to  $x$ -axis i.e. there exists atleast one real number  $c$  in  $(a, b)$  such that  $f'(c) = 0$ . [see figure (a) above]

There may exist more than one point between  $A$  and  $B$ , the tangents at which are parallel to  $x$ -axis [as shown in Figure (b)] i.e. there exists more than one real number  $c$  in  $(a, b)$  such that  $f'(c) = 0$ . Rolle's theorem ensures the existence of atleast one real number  $c$  in  $(a, b)$  such that  $f'(c) = 0$ .

**Remarks:**

1. Rolle's theorem fails even if one of the three conditions is not satisfied by the function.
2. The converse of Rolle's theorem is not true, since,  $f'(x)$  may be zero at a point in  $(a, b)$  without satisfying all the three conditions of Rolle's theorem.

**Example 1.**

Verify Rolle's theorem for the following functions:

- (a)  $f(x) = x^2 + x - 6$  in  $[-3, 2]$
- (b)  $f(x) = (x - 1)(x - 2)^2$  in  $[1, 2]$
- (c)  $f(x) = (x^2 - 1)(x - 2)$  in  $[-1, 2]$

**Solution:**

- (a) Given  $f(x) = x^2 + x - 6$  ... (i)

(i) As  $f(x)$  is a polynomial function, it is continuous in  $[-3, 2]$ .

(ii)  $f(x)$  being a polynomial function is derivable in  $(-3, 2)$

(iii)  $f(-3) = (-3)^2 - 3 - 6 = 0$ ,  $f(2) = 2^2 + 2 - 6 = 0 \Rightarrow f(-3) = f(2)$

Thus, all the three conditions of Rolle's theorem are satisfied, therefore, there exists atleast one real number  $c$  in  $(-3, 2)$  such that  $f'(x) = 2x + 1$ .

Differentiating (i) w.r.t.  $x$ , we get  $f'(x) = 2x + 1$ .

$$\text{Now } f'(c) = 0 \Rightarrow 2c + 1 = 0 \Rightarrow c = -\frac{1}{2}.$$

$$\text{So there exists } -\frac{1}{2} \in (-3, 2) \text{ such that } f'\left(-\frac{1}{2}\right) = 0$$

Hence, Rolle's theorem is verified.

- (b) Given  $f(x) = (x - 1)(x - 2)^2$  ... (i)

(i) Since  $f(x)$  is a polynomial function, it is continuous is  $[1, 2]$ .

(ii)  $f(x)$  being a polynomial function is derivable in  $(1, 2)$ .

(iii)  $f(1) = (1 - 1)(1 - 2)^2 = 0$ ,  $f(2) = (2 - 1)(2 - 2)^2 = 0 \Rightarrow f(1) = f(2)$

Thus, all the three conditions of Rolle's theorem are satisfied, therefore, there exists atleast one real number  $c$  in  $(1, 2)$  such that  $f'(c) = 0$ .

Differentiating (i) w.r.t.  $x$ , we get

$$\begin{aligned} f'(x) &= (x - 1) \cdot 2(x - 2) + (x - 2)^2 \cdot 1 \\ &= (x - 2)(2x - 2 + x - 2) \\ &= (x - 2)(3x - 4) \end{aligned}$$

$$\text{Now } f'(c) = 0$$

$$\Rightarrow (c - 2)(3c - 4) = 0$$

$$\Rightarrow c = 2, \frac{4}{3}$$

But  $c \in (1, 2)$ , therefore,  $c = \frac{4}{3}$ .

So, there exists  $\frac{4}{3} \in (1, 2)$  such that  $f'(\frac{4}{3}) = 0$

Hence, Rolle's theorem is verified.

(c) Given  $f(x) = (x^2 - 1)(x - 2)$  ... (i)

(i) Since  $f(x)$  is a polynomial function, it is continuous in  $[-1, 2]$ .

(ii)  $f(x)$  being a polynomial function is derivable in  $(-1, 2)$ .

(iii)  $f(-1) = (1 - 1)(1 - 2) = 0$ ,  $f(2) = (4 - 1)(2 - 2) = 0 \Rightarrow f(-1) = f(2)$

Thus, all the three conditions of Rolle's theorem are satisfied, therefore, there exists atleast one real number  $c$  in  $(-1, 2)$  such that  $f'(c) = 0$ .

Differentiating (i) w.r.t.  $x$ , we get

$$f'(x) = (x^1 - 1) \cdot 1 + (x - 2) \cdot 2x = 3x^2 - 4x - 1.$$

$$\text{Now } f'(c) = 0 \Rightarrow 3c^2 - 4c - 1 = 0$$

$$\Rightarrow c = \frac{4 \pm \sqrt{16 - 4 \cdot 3(-1)}}{2 \cdot 3} = \frac{2 \pm \sqrt{7}}{3}$$

Also  $-1 < \frac{2 - \sqrt{7}}{3} < \frac{2 + \sqrt{7}}{3} < 2 \Rightarrow \frac{2 - \sqrt{7}}{3}$  and  $\frac{2 + \sqrt{7}}{3}$  both lie in  $(-1, 2)$ .

So there exist two real numbers  $\frac{2 - \sqrt{7}}{3}$  and  $\frac{2 + \sqrt{7}}{3}$  in  $(-1, 2)$  such that

$$f'\left(\frac{2 - \sqrt{7}}{3}\right) = 0 \text{ and } f'\left(\frac{2 + \sqrt{7}}{3}\right) = 0$$

Hence, Rolle's theorem is verified.

### Example 2.

Verify Rolle's theorem for the following functions and find point (or points) where the derivative vanishes:

$$f(x) = \sin x + \cos x \text{ in } \left[0, \frac{\pi}{2}\right]$$

### Solution:

Given:  $f(x) = \sin x + \cos x$  ... (i)

(a)  $f(x)$  is continuous in  $\left[0, \frac{\pi}{2}\right]$

(b)  $f(x)$  is derivable in  $\left[0, \frac{\pi}{2}\right]$  and

(c)  $f(0) = \sin 0 + \cos 0 = 0 + 1 = 1$ ,

$$f\left(\frac{\pi}{2}\right) = \sin \frac{\pi}{2} + \cos \frac{\pi}{2} = 1 + 0 = 1 \Rightarrow f(0) = f\left(\frac{\pi}{2}\right).$$

Thus, all the three conditions of Rolle's theorem are satisfied, therefore, there exists atleast one real number  $c$  in  $\left(0, \frac{\pi}{2}\right)$  such that  $f'(c) = 0$ .

Differentiating (i) w.r.t.  $x$ , we get

$$f'(x) = \cos x - \sin x$$

$$\text{Now } f'(c) = 0 \Rightarrow \cos c - \sin c = 0 \Rightarrow c = 1$$

$$\Rightarrow c = \frac{\pi}{4}, \frac{5\pi}{4}, \frac{9\pi}{4}, -\frac{3\pi}{4}, \dots \text{ but } c \in \left(0, \frac{\pi}{2}\right) \Rightarrow c = \frac{\pi}{4}.$$