

① Q 92 p. 793 (Thomas's Calculus
George B. Thomas, Jr. 12 edition)

$$\text{Let } f(x,y) = \begin{cases} 0 & , \quad x^2 < y < 2x^2 \\ 1 & , \quad \text{otherwise} \end{cases}$$

Show that $f_x(0,0)$ and $f_y(0,0)$ exist,
but f is not differentiable at $(0,0)$

② Math 2010 D, Problem set 6 : Q6.

$$\text{Let } f(x,y) = \begin{cases} x^3 \sin \frac{1}{x^2} + y^3 \sin \frac{1}{y^2} & \text{if } xy \neq 0 \\ 0 & \text{if } xy = 0 \end{cases}$$

(a) Find $\frac{\partial f}{\partial x}(0,0)$ and $\frac{\partial f}{\partial y}(0,0)$

(b) Prove that f is differentiable at $(0,0)$.

③ If $f: \mathbb{R}^n \longrightarrow \mathbb{R}^1$ is a linear map,
then the total derivative $Df(\vec{a})$ at the point \vec{a}

is f . $[Df(\vec{a}) = f]$

\uparrow
a $1 \times n$ matrix $\quad \uparrow$ a mapping: $\mathbb{R}^n \rightarrow \mathbb{R}^1$

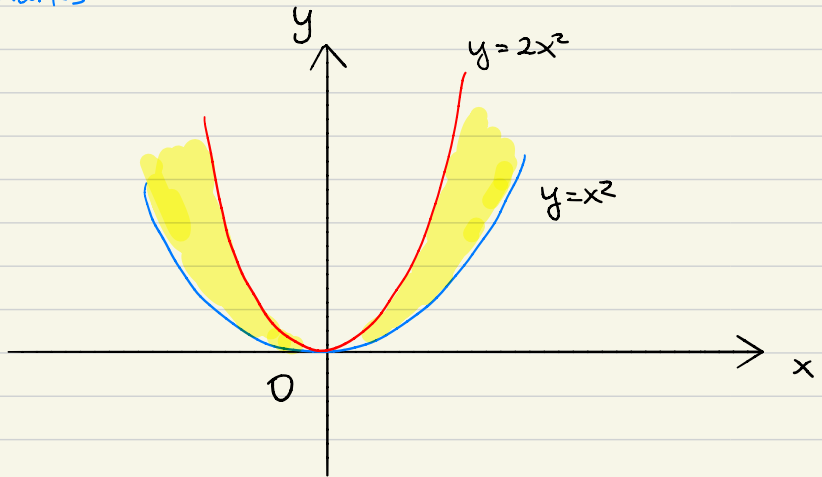
Solution

1.

$$f(x,y) = \begin{cases} 0 & \text{if } x^2 < y < 2x^2 \\ 1 & \text{otherwise} \end{cases}$$

Remarks

①



The function $f(x,y)$ is discontinuous at $(0,0)$

Consider the curve $\sigma(t) = (t, \frac{3}{2}t^2) = (x,y)$
(in xy -coordinate)

Checked that $\sigma(t)$ lies inside the shaded region

when $t \neq 0$.

$$\therefore f(\sigma(t)) = 0 \quad \text{if } t \neq 0$$

Note that

$$(i) \quad \sigma(t) \rightarrow 0 \quad \text{as } t \rightarrow 0$$

$$(ii) \quad f(\sigma(t)) = 0 \quad \text{for } t \neq 0$$

$$(iii) \quad f(0, y) = 1 \quad \text{for } y \neq 0$$

Conclusion : f has non-removable discontinuity

$$\text{at } (0, 0) \quad \left(\lim_{t \rightarrow 0} f(\sigma(t)) = 0, \lim_{y \rightarrow 0} f(0, y) = 1 \right)$$

$\therefore f$ is not differentiable at $(0, 0)$

Moreover,

$$f_x(0, 0) = \lim_{x \rightarrow 0} \frac{f(x, 0) - f(0, 0)}{x}$$

$$\left(\because x < 0 \text{ is false, } \right. \\ \left. f(x, 0) = 1 \right) = \lim_{x \rightarrow 0} \frac{1 - 1}{x} = 0$$

$$f_y(0, 0) = \lim_{y \rightarrow 0} \frac{f(0, y) - f(0, 0)}{y}$$

$$\left(\because 0 < y < 0 \text{ is false, } \right. \\ \left. f(0, y) = 1 \right) = \lim_{y \rightarrow 0} \frac{1 - 1}{y} = 0$$

$$\therefore f_x(0, 0) = f_y(0, 0) = 0 \quad \text{exists}$$

Remark: Good exercise.

① Indeed, $\left[\frac{\partial f}{\partial \vec{u}} = 0 \text{ for any unit vector } \vec{u} \right]$

This is an example that every directional derivative exists, but the function is not differentiable.

② Warning: You cannot deduce that $\frac{\partial f}{\partial \vec{u}} = 0$ due to $\frac{\partial f}{\partial x} = 0 = \frac{\partial f}{\partial y}$, when f is NOT differentiable at that point.

Example: Lecture notes 6 p. 79

$$f(x,y) = \begin{cases} \frac{xy}{x^2+y^2} & \text{for } (x,y) \neq (0,0) \\ 0 & \text{for } (x,y) = (0,0) \end{cases}$$

$\left(\frac{\partial f}{\partial x}(0,0) = 0 = \frac{\partial f}{\partial y}(0,0) \right)$, but

$$\frac{\partial f}{\partial \vec{u}}(0,0) = \lim_{r \rightarrow 0} \frac{f(r \cos \theta, r \sin \theta)}{r} \quad (\vec{u} = (\cos \theta, \sin \theta))$$

$$= \lim_{r \rightarrow 0} \frac{r^2 \cos \theta \sin \theta}{r^3} = \lim_{r \rightarrow 0} \frac{\cos \theta \sin \theta}{r}$$

even does not exist when $\theta \neq 0, \frac{\pi}{2}, \pi, \frac{3\pi}{2}$

2.

$$f(x,y) = \begin{cases} x^3 \sin \frac{1}{x^2} + y^3 \sin \frac{1}{y^2} & \text{if } xy \neq 0 \\ 0 & \text{if } xy = 0 \end{cases}$$

$$(a) \quad \frac{\partial f}{\partial x}(0,0) = \lim_{x \rightarrow 0} \frac{f(x,0) - f(0,0)}{x} = 0$$

$$\frac{\partial f}{\partial y}(0,0) = \lim_{y \rightarrow 0} \frac{f(0,y) - f(0,0)}{y} = 0$$

(b) If f is differentiable at $(0,0)$, then

$$Df(0,0) = \left(\frac{\partial f}{\partial x}(0,0), \frac{\partial f}{\partial y}(0,0) \right)$$

$$= (0,0)$$

Let $\vec{h} = (h_1, h_2)$, let $\vec{1} = (0,0)$

$$\frac{1}{|\vec{h}|} [f(\vec{h}) - f(0,0) - \vec{1} \cdot \vec{h}]$$

$$= \begin{cases} \frac{1}{\sqrt{h_1^2 + h_2^2}} \left[h_1^3 \sin \frac{1}{h_1^2} + h_2^3 \sin \frac{1}{h_2^2} \right] & \text{if } h_1 h_2 \neq 0 \\ 0 & \text{if } h_1 h_2 = 0 \end{cases}$$

put $h_1 = r \cos \theta$, $h_2 = r \sin \theta$

$$= \begin{cases} r^2 \left(\cos^3 \theta \sin \frac{1}{h_1^2} + \sin^3 \theta \sin \frac{1}{h_2^2} \right) & \text{if } h_1, h_2 \neq 0 \\ 0 & \text{if } h_1, h_2 = 0 \end{cases}$$

Note $|\vec{h}| = r$

Sandwich thm

$$\Rightarrow \lim_{|\vec{h}| \rightarrow 0} \frac{1}{|\vec{h}|} [f(\vec{h}) - f(\vec{0}) - \vec{T} \cdot \vec{h}] = 0$$

$\therefore f$ is differentiable at $(0,0)$ with total derivative $Df(0,0) = \langle 0, 0 \rangle$

✱

3. A function $f: \mathbb{R}^n \rightarrow \mathbb{R}^m$ is said to be a **linear map** if

for every scalar $\alpha \in \mathbb{R}$, vector $\vec{x}, \vec{y} \in \mathbb{R}^n$,

we have $f(\alpha \vec{x} + \vec{y}) = \alpha f(\vec{x}) + f(\vec{y})$

Thm: Every linear map $f: \mathbb{R}^n \rightarrow \mathbb{R}^m$

is just a matrix multiplication mapping.

More precisely, you can always find a

$m \times n$ matrix M so that

$$f(\vec{v}) = M\vec{v} \quad \text{for every } v \in \mathbb{R}^n$$

Remark :

↑ Matrix multiplication

① The choice of matrix M depends on the function f

② Once your M is chosen ,

$$f(\vec{v}) = M\vec{v} \quad \text{for every } v \in \mathbb{R}^n$$

$$\textcircled{3} \quad M = \left(\begin{array}{c|c|c|c} | & | & & | \\ f(\vec{e}_1) & f(\vec{e}_2) & \dots & f(\vec{e}_n) \\ | & | & & | \end{array} \right)$$

$$\textcircled{4} \quad e_i \in \mathbb{R}^n, \quad e_i = \begin{pmatrix} 0 \\ \vdots \\ 0 \\ 1 \\ 0 \\ \vdots \\ 0 \end{pmatrix} \leftarrow \text{ith position}$$

$$f(\vec{e}_i) \in \mathbb{R}^m \quad (\because f: \mathbb{R}^n \rightarrow \mathbb{R}^m)$$

You can see easily that M is

really a $m \times n$ matrix

⑤ Verification: Let $\vec{v} \in \mathbb{R}^n$, there are some $\alpha_1, \alpha_2, \dots, \alpha_n \in \mathbb{R}$, so that

$$\vec{v} = \alpha_1 \vec{e}_1 + \alpha_2 \vec{e}_2 + \dots + \alpha_n \vec{e}_n$$

$$\begin{aligned} f(\vec{v}) &= f(\alpha_1 \vec{e}_1 + \alpha_2 \vec{e}_2 + \dots + \alpha_n \vec{e}_n) \\ &= \alpha_1 f(\vec{e}_1) + \alpha_2 f(\vec{e}_2) + \dots + \alpha_n f(\vec{e}_n) \\ &= \begin{pmatrix} | & | & & | \\ f(\vec{e}_1) & f(\vec{e}_2) & \dots & f(\vec{e}_n) \\ | & | & & | \end{pmatrix} \begin{pmatrix} \alpha_1 \\ \alpha_2 \\ \vdots \\ \alpha_n \end{pmatrix} \\ &= M(\alpha_1 \vec{e}_1 + \alpha_2 \vec{e}_2 + \dots + \alpha_n \vec{e}_n) \\ &= M\vec{v}. \end{aligned}$$

✘

Back to our assertion, more precisely,

if M_f is the matrix so that $f(\vec{v}) = M_f \vec{v}$,

then $Df(\vec{a}) = M_f$ for every $\vec{a} \in \mathbb{R}^n$

Proof: $f(\vec{a} + \vec{h}) - f(\vec{a}) - M_f \vec{h}$

$$= f(\vec{a} + \vec{h}) - f(\vec{a}) - f(\vec{h})$$

$$= 0 \quad \forall \vec{h} \in \mathbb{R}^n$$

You may regard \vec{h} as a $n \times 1$ matrix, then this is a matrix multi. only.