

## Section 3.5: Repeated eigenvalues

This is what we called **Case Ia**): two (necessarily real) equal eigenvalues  $\lambda_1 = \lambda_2$  of  $A$ . To shorten the notation, **write  $\lambda$  instead of  $\lambda_1$** .

We suppose  $\lambda \neq 0$ .

A matrix  $A$  with two repeated eigenvalues can have one or two linearly independent eigenvectors.

The form and behavior of the solutions of  $\mathbf{x}' = A\mathbf{x}$  is different according to these two situations.

### Example:

Show that  $A = \begin{bmatrix} -1 & 0 \\ 0 & -1 \end{bmatrix}$  and  $B = \begin{bmatrix} -1 & 1 \\ 0 & -1 \end{bmatrix}$  have one repeated eigenvalue  $\lambda$ .

Find  $\lambda$ .

Show that  $A$  has two linearly independent eigenvectors of eigenvalue  $\lambda$  whereas  $B$  does not.

Consider the system  $\mathbf{x}' = A\mathbf{x}$  where  $A$  is a  $2 \times 2$  matrix with repeated eigenvalue  $\lambda \neq 0$ .

- If there are two linearly independent eigenvectors  $\mathbf{v}_1$  and  $\mathbf{v}_2$  of eigenvalue  $\lambda$ .  
Then two linearly independent solutions of  $\mathbf{x}' = A\mathbf{x}$  are

$$\mathbf{x}_1(t) = e^{\lambda t} \mathbf{v}_1 \quad \text{and} \quad \mathbf{x}_2(t) = e^{\lambda t} \mathbf{v}_2$$

The **general solution** is

$$\mathbf{x}(t) = C_1 \mathbf{x}_1(t) + C_2 \mathbf{x}_2(t) = C_1 e^{\lambda t} \mathbf{v}_1 + C_2 e^{\lambda t} \mathbf{v}_2.$$

- If there is only one linearly independent eigenvector  $\mathbf{v}_1$  of eigenvalue  $\lambda$ .  
Then two linearly independent solutions of  $\mathbf{x}' = A\mathbf{x}$  are

$$\mathbf{x}_1(t) = t e^{\lambda t} \mathbf{v}_1 \quad \text{and} \quad \mathbf{x}_2(t) = e^{\lambda t} \mathbf{w}$$

where  $\mathbf{w}$  satisfies  $(A - \lambda I)\mathbf{w} = \mathbf{v}_1$

(we say that  $\mathbf{w}$  is a *generalized eigenvector* corresponding to the eigenvalue  $\lambda$ ).

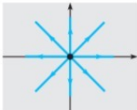
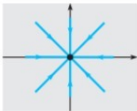
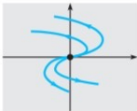
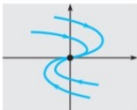
The **general solution** is

$$\mathbf{x}(t) = C_1 \mathbf{x}_1(t) + C_2 \mathbf{x}_2(t) = C_1 e^{\lambda t} \mathbf{v}_1 + C_2 t e^{\lambda t} \mathbf{w}.$$

$\mathbf{x}_{\text{eq}} = \begin{pmatrix} 0 \\ 0 \end{pmatrix}$  is the unique critical point. It is the origin  $(0, 0)$  of the phase plane.

TABLE 3.5.1

Phase portraits for  $\mathbf{x}' = \mathbf{A}\mathbf{x}$  when  $\mathbf{A}$  has a single repeated eigenvalue.

Nature of $\mathbf{A}$ and Eigenvalues	Sample Phase Portrait	Type of Critical Point	Stability
$\mathbf{A} = \begin{pmatrix} \lambda & 0 \\ 0 & \lambda \end{pmatrix}$ $\lambda > 0$		$(0, 0)$ is an <b>unstable proper node</b> . <i>Note:</i> $(0, 0)$ is also called an <b>unstable star node</b> .	Unstable
$\mathbf{A} = \begin{pmatrix} \lambda & 0 \\ 0 & \lambda \end{pmatrix}$ $\lambda < 0$		$(0, 0)$ is a <b>stable proper node</b> . <i>Note:</i> $(0, 0)$ is also called a <b>stable star node</b> .	Asymptotically stable
$\mathbf{A}$ is not diagonal. $\lambda > 0$		$(0, 0)$ is an <b>unstable improper node</b> . <i>Note:</i> $(0, 0)$ is also called an <b>unstable degenerate node</b> .	Unstable
$\mathbf{A}$ is not diagonal. $\lambda < 0$		$(0, 0)$ is a <b>stable improper node</b> . <i>Note:</i> $(0, 0)$ is also called a <b>stable degenerate node</b> .	Asymptotically stable

J. BRENNAN &amp; W. BOYCE, DIFFERENTIAL EQUATIONS, P. 184