

## Explicit Euler method

$$y_{k+1} = y_k + h_k f(x_k, y_k), \quad k = 0, 1, \dots$$

## Local error

$$L_k = \frac{1}{2} y''(x_k + \tau_k h_k) h_k^2, \quad k = 0, 1, \dots$$

## Approximation of $y''$

$$y''(\cdot) \approx y''_{k-1} := \frac{y'_k - y'_{k-1}}{x_k - x_{k-1}} = \frac{f(x_k, y_k) - f(x_{k-1}, y_{k-1})}{x_k - x_{k-1}}, \quad k = 1, 2, \dots$$

- the goal:  $L_k \leq \text{TOL}$ ,  $\text{TOL} > 0$  is given,
- the idea: set  $h_k$  such that  $L_k \approx \text{TOL}$ .

## Optimal size of the time step

$$h_k^{\text{opt}} = \sqrt{\frac{2\text{TOL}}{y''_k(\cdot)}}, \quad k = 0, 1, \dots$$

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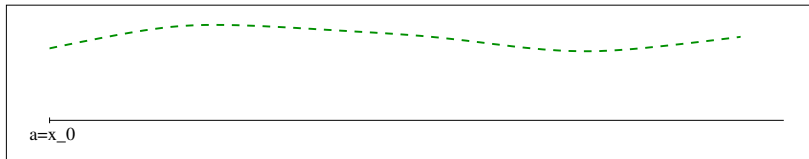
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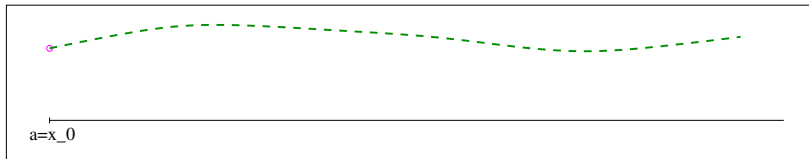
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adaptive choice of time step “guarantees” the stability of method



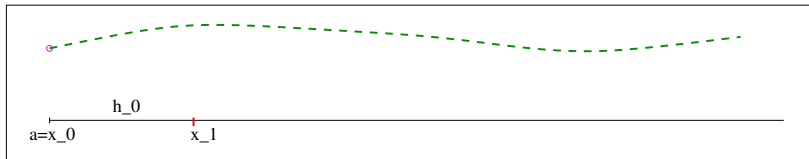
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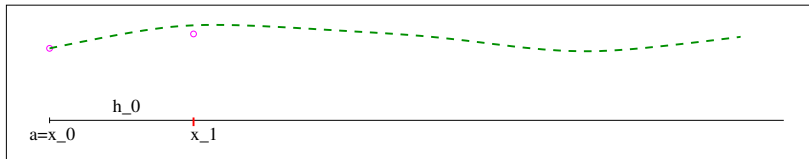
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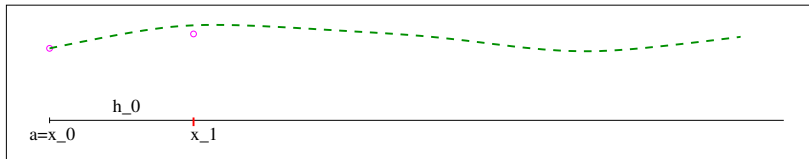
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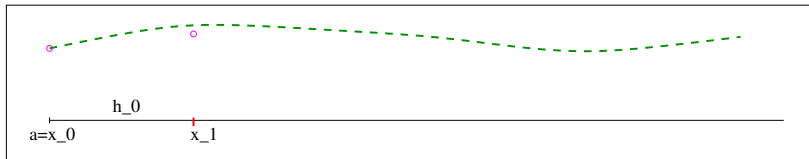
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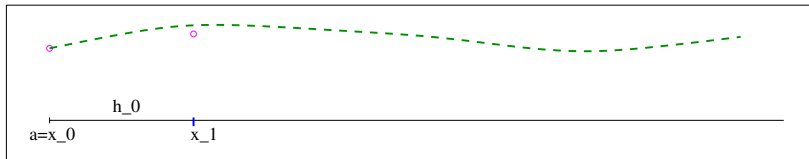
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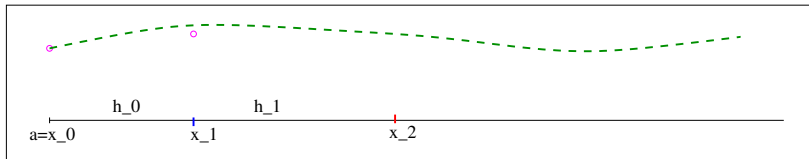
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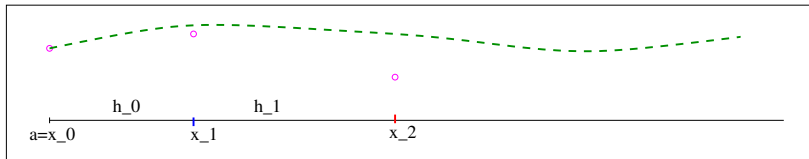
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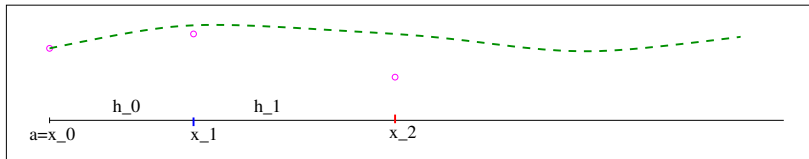
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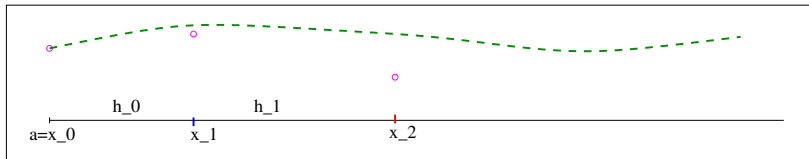
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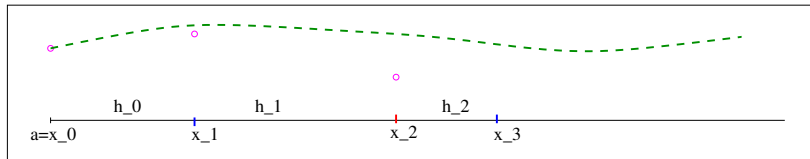
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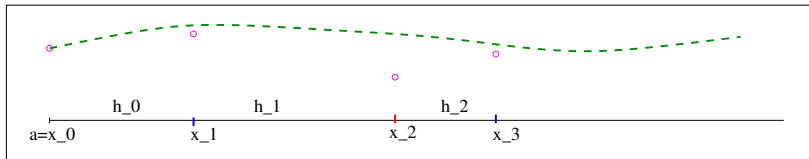
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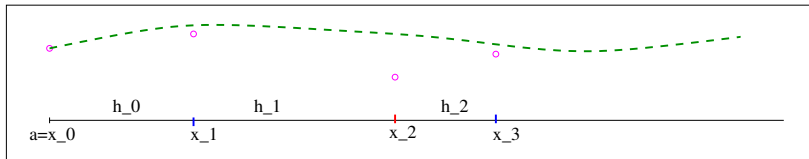
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- compute  $y_3 = y_2 \dots$  with  $L_2 \leq \text{TOL}$

adaptive choice of time step “guarantees” the stability of method



- $y_0$  given by IC
- propose initial step  $h_0$
- compute  $y_1 = y_0 + h_0 f(x_0, y_0)$ ,
- estimate  $L_0 \approx \frac{1}{2} h_0^2 y_0''$ ,  $y_0'' = \frac{f(x_1, y_1) - f(x_0, y_0)}{x_1 - x_0}$
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- **compute  $y_3 = y_2 \dots$  with  $L_2 \leq \text{TOL}$**

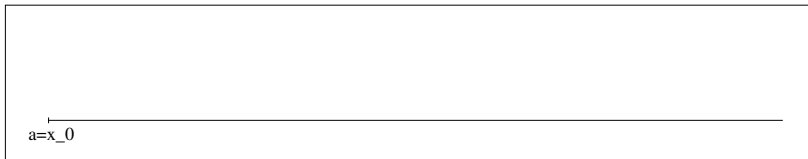
adaptive choice of time step “guarantees” the stability of method



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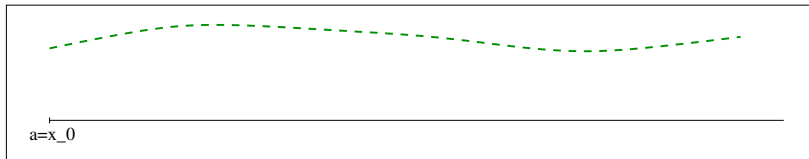
adaptive choice of time step “guarantees” the stability of method





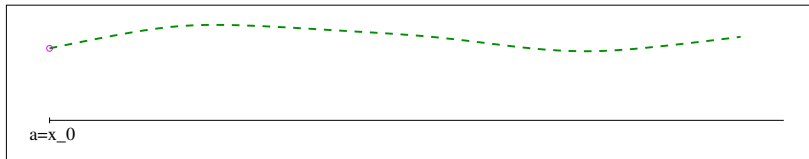
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- step  $k = 1$  is REFUSED
- set  $h_1 := h_1^{\text{opt}} = \sqrt{2\text{TOL}/y_1''}$ ,
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adaptive choice of time step guarantees the accuracy of method



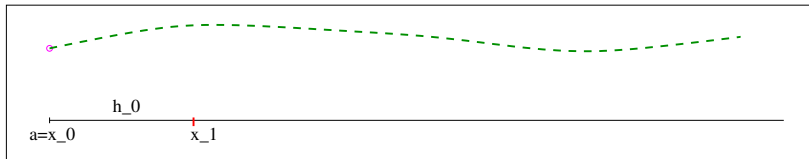
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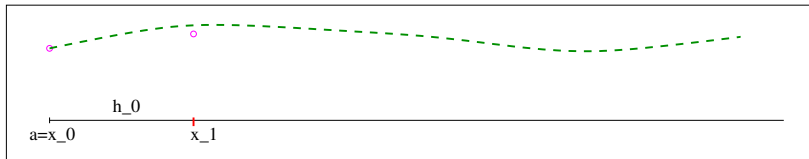
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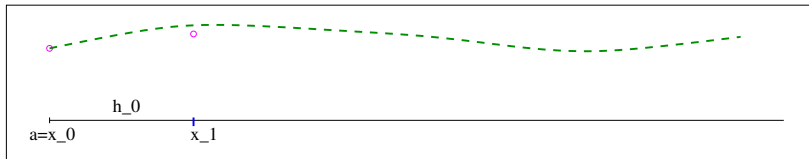
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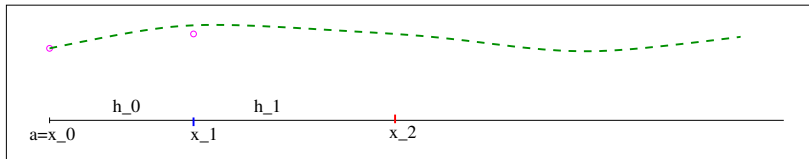
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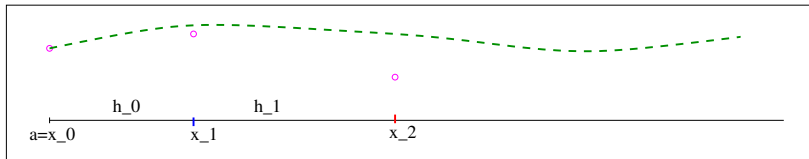
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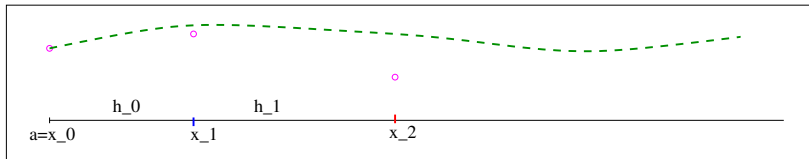
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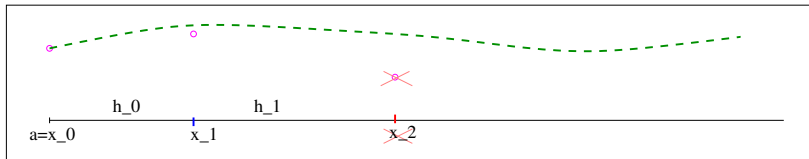
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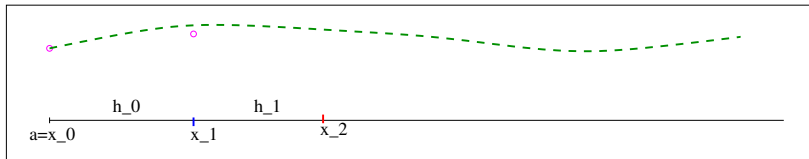
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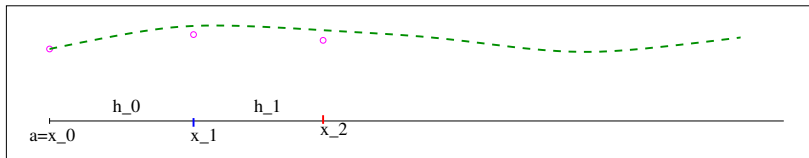
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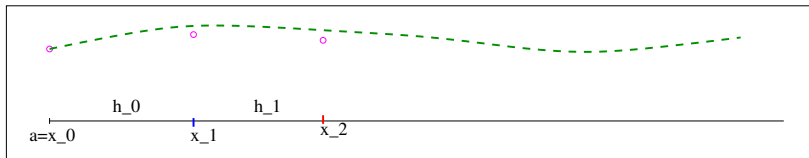
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