

Solving some partial q -differential equations using transformation methods

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Abstract In this paper, we introduce the concepts of transformed functions and q -difference inverse transforms. Then, we apply them to solve some partial q -difference equations. Finally, we provide four examples to show how we can benefit from the obtained results.

1 Introduction

The subject of q -calculus started in the nineteenth century in intense works by Jackson [20], Carmichael [11], Mason [23], Trjitzinsky [29], Adams [1], Mason [23], and Trjitzinsky [29]. Recently, q -calculus has been a goal of some recent studies such as [4, 7, 9].

The q -difference has a lot of applications in different fields of mathematics such as number theory, statistical physics [24], fractal geometry [14],[15], quantum mechanics, orthogonal polynomials [19] and other sciences including theory of relativity [5], mechanics and quantum theory.

In the last years, partial q -difference equations are generally studied by various methods of separation of variables, by the techniques of Lie symmetry, using q -integral transforms [3, 16, 17, 10, 22].

In this paper, we explain the solution of the partial q -difference equations using reduced transformation method.

First, let us recall some basic concepts of q -calculus mentioned in ([5, 6, 26, 12, 13, 18, 20, 21, 28]). The shifted factorial $(r)_n$ is defined by:

$$\begin{aligned}(r; q)_0 &= 1, \\(r; q)_n &= (1-r)(1-qr)(1-q^2r)(1-q^3r)\dots(1-q^{n-1}r) \\ &= \prod_{k=0}^{n-1} (1-q^k r), \quad n \in \mathbb{N}, 0 < q < 1, \text{ and } r \in \mathbb{C}.\end{aligned}$$

A complex number r is defined by:

$$\begin{aligned}[r]_q &= 1 + q + q^2 + \dots + q^{r-1} \\ &= \frac{1-q^r}{1-q}, \quad q \in \mathbb{C} - \{1\}; r \in \mathbb{C}\end{aligned}$$

and the factorial function is

$$\begin{aligned}[r]_q! &= [1]_q [2]_q [3]_q \dots [r]_q \\ &= \prod_{k=1}^r [k]_q, \quad q \neq 1; k \in \mathbb{N}, 0 \leq q \leq 1.\end{aligned}$$

The q -binomial coefficient $\begin{bmatrix} r \\ k \end{bmatrix}_q$ is defined by:

$$\begin{bmatrix} r \\ k \end{bmatrix}_q = \frac{[r]_q!}{[r-k]_q! [k]_q!}, \quad r = 0, 1, 2, \dots, k.$$

Transformation Methods For Partial Differential Equations

G Psacharopoulos



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Transform Methods for Solving Partial Differential Equations Dean G. Duffy, 1994-02-16 For most scientists and engineers the only analytic technique for solving linear partial differential equations is separation of variables In **Transform Methods for Solving Partial Differential Equations** the author uses the power of complex variables to demonstrate how Laplace and Fourier transforms can be harnessed to solve many practical everyday problems experienced by scientists and engineers Unlike many mathematics texts this book provides a step by step analysis of problems taken from scientific and engineering literature Detailed solutions are given in the back of the book This essential text reference draws from the latest literature on transform methods to provide in depth discussions on the joint transform problem the Cagniard de Hoop method and the Wiener Hopf technique Some 1 500 references are included as well [Transformation Methods for Nonlinear Partial Differential Equations](#) Dominic G. B. Edelen, Jian-hua Wang, 1992 The purpose of the book is to provide research workers in applied mathematics physics and engineering with practical geometric methods for solving systems of nonlinear partial differential equations The first two chapters provide an introduction to the more or less classical results of Lie dealing with symmetries and similarity solutions The results however are presented in the context of contact manifolds rather than the usual jet bundle formulation and provide a number of new conclusions The remaining three chapters present essentially new methods of solution that are based on recent publications of the authors The text contains numerous fully worked examples so that the reader can fully appreciate the power and scope of the new methods In effect the problem of solving systems of nonlinear partial differential equations is reduced to the problem of solving families of autonomous ordinary differential equations This allows the graphs of solutions of the system of partial differential equations to be realized as certain leaves of a foliation of an appropriately defined contact manifold In fact it is often possible to obtain families of solutions whose graphs foliate an open subset of the contact manifold These ideas are extended in the final chapter by developing the theory of transformations that map a foliation of a contact manifold onto a foliation This analysis gives rise to results of surprising depth and practical significance In particular an extended Hamilton Jacobi method for solving systems of partial differential equations is obtained **Transformation Methods For Nonlinear Partial Differential Equations** Dominic G B Edelen, Jian-hua Wang, 1992-06-09 The purpose of the book is to provide research workers in applied mathematics physics and engineering with practical geometric methods for solving systems of nonlinear partial differential equations The first two chapters provide an introduction to the more or less classical results of Lie dealing with symmetries and similarity solutions The results however are presented in the context of contact manifolds rather than the usual jet bundle formulation and provide a number of new conclusions The remaining three chapters present essentially new methods of solution that are based on recent publications of the authors The text contains numerous fully worked examples so that the reader can fully appreciate the power and scope of the new methods In effect the problem of solving systems of nonlinear

partial differential equations is reduced to the problem of solving families of autonomous ordinary differential equations This allows the graphs of solutions of the system of partial differential equations to be realized as certain leaves of a foliation of an appropriately defined contact manifold In fact it is often possible to obtain families of solutions whose graphs foliate an open subset of the contact manifold These ideas are extended in the final chapter by developing the theory of transformations that map a foliation of a contact manifold onto a foliation This analysis gives rise to results of surprising depth and practical significance In particular an extended Hamilton Jacobi method for solving systems of partial differential equations is obtained

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