

$$\begin{aligned}
\textcircled{1} \quad & \{d(e^x \sin y) \wedge dx\} \wedge \{d[\log(yz)]\} = \\
& = \{[d(e^x \sin y)] \wedge dx\} \wedge \left\{ \left[\frac{\partial}{\partial x} \log(yz) dx + \frac{\partial}{\partial y} \log(yz) dy + \frac{\partial}{\partial z} \log(yz) dz \right] \right\} = \\
& = \left\{ \left[\frac{\partial}{\partial x} e^x \sin y \right] dx \wedge dx + \left[\frac{\partial}{\partial y} e^x \sin y \right] dy \wedge dx + \left[\frac{\partial}{\partial z} e^x \sin y \right] dz \wedge dx \right\} \\
& \wedge \left\{ 0 \cdot dx + \frac{1}{y} dy + \frac{1}{z} dz \right\} = \\
& = \{0 + e^x \cos y dy \wedge dx + 0\} \wedge \left\{ \frac{1}{y} dy + \frac{1}{z} dz \right\} = \\
& = (e^x \cos y) \frac{1}{y} dy \wedge dx \wedge dy + (e^x \cos y) \frac{1}{z} dx \wedge dy \wedge dz = \\
& = 0 + \frac{e^x \cos y}{z} dx \wedge dy \wedge dz
\end{aligned}$$

$$(2) \quad S(t_1, t_2) = [t_1^2, t_2^2, t_1^2 + t_2^2] \quad (t_1, t_2 \in [0, 1]),$$

$$\Omega = \underbrace{xy \, dx \wedge dy}_{\Omega_1} + \underbrace{xyz \, dy \wedge dz}_{\Omega_2}$$

$$\int_S \Omega = \int_S \Omega_1 + \int_S \Omega_2$$

$$\int_S \Omega_1 = \int_{t_1=0}^1 \int_{t_2=0}^1 t_1^2 t_2^2 (dt_1^2) \wedge (dt_2^2) =$$

$$x = t_1^2 \quad y = t_2^2 \quad z = t_1^2 + t_2^2$$

$$= \int_{t_1=0}^1 \int_{t_2=0}^1 t_1^2 t_2^2 (2t_1 dt_1) \wedge (2t_2 dt_2) =$$

$$= \int_{t_1=0}^1 \int_{t_2=0}^1 t_1^2 t_2^2 (2t_1)(2t_2) dt_1 dt_2 =$$

$$= \int_{t_1=0}^1 \int_{t_2=0}^1 4 t_1^3 t_2^3 dt_2 dt_1 \quad \left[= \int_{t_2=0}^1 \int_{t_1=0}^1 4 t_1^3 t_2^3 dt_1 dt_2 \right]$$

$$= \int_{t_1=0}^1 4 t_1^3 \cdot \frac{1}{4} t_2^4 \Big|_{t_2=0}^1 dt_1 = \int_{t_1=0}^1 4 t_1^3 \cdot \frac{1}{4} dt_1 =$$

$$= \int_{t_1=0}^1 t_1^3 dt_1 = \frac{1}{4}$$

$$\int_{\Omega} z = \int \int xy z \, dy \wedge dz = \begin{matrix} \uparrow \\ x=t_1^2 \quad y=t_2^2 \quad z=t_1^2+t_2^2 \end{matrix}$$

$$= \int_{t_1=0}^1 \int_{t_2=0}^1 t_1^2 t_2^2 (t_1^2+t_2^2) (dt_2^2) \wedge [d(t_1^2+t_2^2)] =$$

$$= \int_{t_1=0}^1 \int_{t_2=0}^1 [t_1^4 t_2^2 + t_1^2 t_2^4] (2t_2 dt_2) \wedge (2t_1 dt_1 + 2t_2 dt_2) =$$

$$= \int_{t_1=0}^1 \int_{t_2=0}^1 [t_1^4 t_2^2 + t_1^2 t_2^4] [4t_1 t_2^2 dt_1 dt_2 + 4t_2^2 dt_2 dt_1]$$

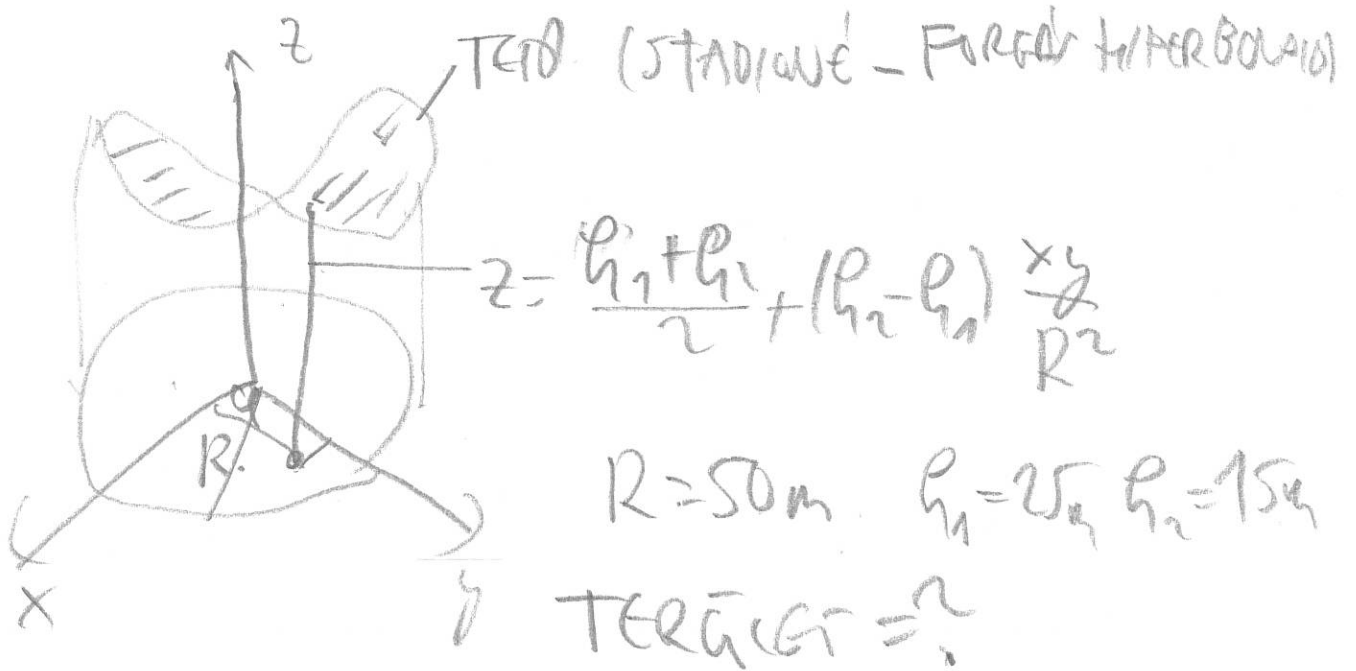
$$= \int_{t_1=0}^1 \int_{t_2=0}^1 4 [t_1^5 t_2^2 + t_1^3 t_2^6] dt_2 \wedge dt_1 \stackrel{\ominus}{=} \int_{t_1=0}^1 \int_{t_2=0}^1 (-4) (t_1^5 t_2^2 + t_1^3 t_2^6) dt_1 \wedge dt_2 =$$

$$= \int_{t_1=0}^1 \int_{t_2=0}^1 (-4) (t_1^5 t_2^2 + t_1^3 t_2^6) dt_1 dt_2 =$$

$$= (-4) \left(\frac{1}{6} \cdot \frac{1}{5} + \frac{1}{4} \cdot \frac{1}{7} \right) = -\frac{2}{15} - \frac{1}{7}$$

$$\int_{\Omega} z = \frac{1}{4} - \frac{2}{15} - \frac{1}{7} = \frac{105 - 28 - 60}{420} = \frac{17}{420}$$

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$$TERO = \int_{PARTAR} F \, d\text{det} = \int_Q \sqrt{(dx \, dy)^2 + (dy \, dz)^2 + (dz \, dx)^2}$$

PARAMETERISIERUNG

$$x = r \cos \varphi \quad y = R \sin \varphi \quad z = \frac{h_1 + h_2}{2} + (h_2 - h_1) \frac{r^2 \cos \varphi \sin \varphi}{R^2}$$

PARAMETERBEREICH: $R \in [0, 50]$ $\varphi \in [0, 2\pi]$

$$Q : [0, 50] \times [0, 2\pi] \rightarrow \mathbb{R}^3$$

$$(r, \varphi) \mapsto \begin{bmatrix} r \cos \varphi \\ r \sin \varphi \\ \frac{h_1 + h_2}{2} + (h_2 - h_1) \frac{r^2}{R^2} \sin \varphi \cos \varphi \\ \frac{1}{2} \sin 2\varphi \end{bmatrix} \begin{matrix} Q_1 \\ Q_2 \\ Q_3 \\ Q_4 \end{matrix}$$

$$T_{\text{center}} = \int_{r=0}^{R} \int_{\varphi=0}^{2\pi} \sqrt{\det(Q'^T \cdot Q')} \, d\varphi \, dr$$

$$Q' = Q'(r, \varphi) = \begin{bmatrix} \partial Q_1 / \partial r & \partial Q_1 / \partial \varphi \\ \partial Q_2 / \partial r & \partial Q_2 / \partial \varphi \\ \partial Q_3 / \partial r & \partial Q_3 / \partial \varphi \end{bmatrix} =$$

$$= \begin{bmatrix} \cos \varphi & -r \sin \varphi \\ \sin \varphi & r \cos \varphi \\ \frac{(R-r)}{H} \frac{1}{R} \sin \varphi & \frac{(R-r)}{H} \cos \varphi \frac{r}{R} \end{bmatrix}$$

$$Q'^T Q' = \left[\langle Q' \cdot \cos \varphi \mid Q' \cdot \cos \varphi \rangle \right]_{i,j=1}^2 =$$

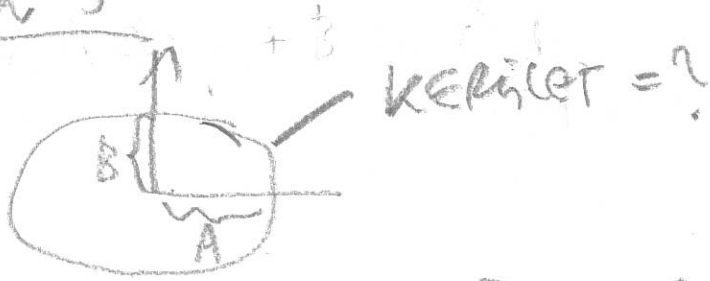
$$= \begin{bmatrix} \cos^2 \varphi + \sin^2 \varphi + \frac{H^2 r^2}{R^4} \sin^2 \varphi & \text{---} \\ \frac{H^2 r^3}{R^4} \sin \varphi \cos \varphi & r + \frac{H^2 r^4}{R^4} \cos^2 \varphi \end{bmatrix} =$$

$$\det(Q'^T Q') = \frac{r^2 (R^4 + H^2 r^2 \cos^2 \varphi + H^2 r^2 \sin^2 \varphi)}{R^4}$$

$$J_{\text{ac}} Q' = \sqrt{\det(Q'^T Q')} = r \sqrt{1 + \frac{H^2 r^2}{R^4}}$$

$$T_{\text{center}} = \int_{r=0}^R \int_{\varphi=0}^{2\pi} \sqrt{1 + \frac{H^2 r^2}{R^4}} \, r^2 \, d\varphi \, dr = \int_{s=0}^{s=R^2} \sqrt{1 + \frac{H^2}{R^2} s} \, ds = \frac{(\sqrt{R^2 + H^2 R^2} - R) R^3}{H^2}$$

Elliptik



$$Q = [0, 2\pi] \ni \varphi \mapsto \begin{bmatrix} A \cos \varphi \\ B \sin \varphi \end{bmatrix}$$



$$[Q([0, 2\pi]) \text{ KONTAK}] = \int_Q \text{Jac} Q \, d\varphi =$$

$$= \int_{\varphi=0}^{2\pi} \sqrt{\det(Q'^T Q')} \, d\varphi$$

$$Q' = \begin{bmatrix} -A \sin \varphi \\ B \cos \varphi \end{bmatrix}$$

$$Q'^T Q' = A^2 \sin^2 \varphi + B^2 \cos^2 \varphi$$

$$\text{KERISET} = \int_{\varphi=0}^{2\pi} \sqrt{A^2 \sin^2 \varphi + B^2 \cos^2 \varphi} \, d\varphi$$

NINCS VE'GGEZ ELEMENI KERISET

→ új specific függvények

ELLIPTIKUS FÜGGVÉNYEK

$$\text{TERFELLET} = \int_{\tau=0}^{50} \int_{\psi=0}^{4\pi} \sqrt{2\tau^2 + 100 \cos^2 \psi} \cdot \frac{1}{2} \, d\psi =$$

$$= \int_{\tau=0}^{50} 2 \cdot \text{Ellipt} \left(\sqrt{\tau^2 + 100}, 10 \right) \, d\tau$$