

# **MathML DocBook Examples working with dblatex**

---

---

**COLLABORATORS**

	<i>TITLE :</i> MathML DocBook Examples working with dblatex		
<i>ACTION</i>	<i>NAME</i>	<i>DATE</i>	<i>SIGNATURE</i>
WRITTEN BY		December 13, 2009	

**REVISION HISTORY**

NUMBER	DATE	DESCRIPTION	NAME

---

---

## Contents

<b>1</b>	<b>This section demonstrates the use of MathML</b>	<b>1</b>
1.1	Basic MathML: Presentation Markups . . . . .	1
1.2	Complex MathML: Content Markups . . . . .	1
1.2.1	Complex MathML 1 . . . . .	2
1.2.2	Complex MathML 2 . . . . .	3
<b>2</b>	<b>LaTeX</b>	<b>3</b>
2.1	Inertial Tensor . . . . .	3
2.2	Change-of-coordinate matrix from body trihedron to element trihedron . . . . .	4

## 1 This section demonstrates the use of MathML

### 1.1 Basic MathML: Presentation Markups

$$E = \sqrt{mc^2} \tag{1}$$

$$\frac{E}{F} \tag{2}$$

$$(E + F) \tag{3}$$

$$A = \begin{bmatrix} x & y \\ z & w \end{bmatrix}. \tag{4}$$

$$E = mc^2 \tag{5}$$

$$\sum 4 + x \tag{6}$$

$$(x + y)^2 \tag{7}$$

### 1.2 Complex MathML: Content Markups

The following examples have been found here: <http://www.grigoriev.ru/svgmath>

1.2.1 Complex MathML 1

Bernoulli Trials	$P(E) = \binom{n}{k} p^k (1-p)^{n-k}$
Cauchy-Schwarz Inequality	$\left( \sum_{k=1}^n a_k b_k \right)^2 \leq \left( \sum_{k=1}^n a_k^2 \right) \left( \sum_{k=1}^n b_k^2 \right)$
Cauchy Formula	$f(z) \cdot \text{Ind}_\gamma(z) = \frac{1}{2\pi i} \oint_\gamma \frac{f(\xi)}{\xi - z} d\xi$
Cross Product	$V_1 \times V_2 = \begin{vmatrix} i & j & k \\ \frac{\partial X}{\partial u} & \frac{\partial Y}{\partial u} & 0 \\ \frac{\partial X}{\partial v} & \frac{\partial Y}{\partial v} & 0 \end{vmatrix}$
Vandermonde Determinant	$\begin{vmatrix} 1 & 1 & \dots & 1 \\ v_1 & v_2 & \dots & v_n \\ v_1^2 & v_2^2 & \dots & v_n^2 \\ \vdots & \vdots & \ddots & \vdots \\ v_1^{n-1} & v_2^{n-1} & \dots & v_n^{n-1} \end{vmatrix} = \prod_{1 \leq i < j \leq n} (v_j - v_i)$
Lorenz Equations	$\begin{aligned} \dot{x} &= \sigma(y-x) \\ \dot{y} &= \rho x - y - xz \\ \dot{z} &= -\beta z + xy \end{aligned}$
Maxwell's Equations	$\begin{cases} \nabla \times \underline{B} - \frac{1}{c} \frac{\partial \underline{E}}{\partial t} = \frac{4\pi}{c} \underline{j} \\ \nabla \cdot \underline{E} = 4\pi \rho \\ \nabla \times \underline{E} + \frac{1}{c} \frac{\partial \underline{B}}{\partial t} = \underline{0} \\ \nabla \cdot \underline{B} = 0 \end{cases}$
Einstein Field Equations	$R_{\mu\nu} - \frac{1}{2} g_{\mu\nu} R = \frac{8\pi G}{c^4} T_{\mu\nu}$
Ramanujan Identity	$\frac{1}{(\sqrt{\phi\sqrt{5}-\phi})e^{\frac{25}{\pi}}} = 1 + \frac{e^{-2\pi}}{1 + \frac{e^{-4\pi}}{1 + \frac{e^{-6\pi}}{1 + \frac{e^{-8\pi}}{1 + \dots}}}}$
Another Ramanujan identity	$\sum_{k=1}^{\infty} \frac{1}{2^{\lfloor k \cdot \phi \rfloor}} = \frac{1}{2^0 + \frac{1}{2^1 + \frac{1}{2^1 + \frac{1}{2^2 + \frac{1}{2^3 + \frac{1}{2^3 + \dots}}}}}}$
Rogers-Ramanujan Identity	$1 + \sum_{k=1}^{\infty} \frac{q^{k^2+k}}{(1-q)(1-q^2)\dots(1-q^k)} = \prod_{j=0}^{\infty} \frac{1}{(1-q^{5j+2})(1-q^{5j+3})}, \text{ for }  q  < 1.$
Commutative Diagram	$\begin{array}{ccc} & & \\ & \downarrow & \uparrow \\ H & \rightarrow & K \end{array}$

### 1.2.2 Complex MathML 2

Quadratic Equation	$x = \frac{-b \pm \sqrt{b^2 - 4ac}}{2a}$
DisplayQuadratic Equation	$x = \frac{-b \pm \sqrt{b^2 - 4ac}}{2a}$
Rational Function	$f(x) = \frac{1-x^2}{1-x^3}$
Rational Function	$f(x) = \frac{(1-x^2)x^3}{1-x^3}$
Rational Function	$f(x) = \frac{(1-x^2)(x^3-5x)}{1-x^3}$
Parametrize Rational Function	$f(x) = \frac{(a_i-x^2)^5}{1-x^3}$
Stacked exponents	$g(z) = e^{-x^2}$
Stacked exponents	$g(z) = e^{-(z-a)^2}$
Stacked exponents	$g(z) = e^{-\sum_{i=0}^{\infty} z^i}$
Stacked exponents	$g(y) = e^{-\sum_{i=0}^{\infty} y_i^2}$
Stacked exponents	$g(z) = e^{-\sum_{i=0}^{\infty} z^{\frac{2}{a-i}}}$
Cross Product	$\begin{pmatrix} x_1-x_2 & x_1-x_4 \\ x_3-x_4 & x_2-x_3 \end{pmatrix}$
Cross Product	$\begin{pmatrix} x_1-x_2 \\ x_3-x_4 \end{pmatrix} \begin{pmatrix} x_1-x_4 \\ x_2-x_3 \end{pmatrix}$
Cross Product	$\begin{pmatrix} x_1-x_2 \\ x_3-x_4 \end{pmatrix} \begin{pmatrix} x_1-x_4 \\ x_2-x_3 \end{pmatrix}$
Cross Product	$\frac{(x_1-x_2)(x_3-x_4)}{(x_1-x_4)(x_2-x_3)}$

## 2 LaTeX

If you are tired of writing equations with MathML, with dblatex you can use the powerful LaTeX equation parser. Here are a few examples.

---

### Note

You have to look at the source code to appreciate how it is easy to write equations with LaTeX.

---

### 2.1 Inertial Tensor

For a  $c$  system of  $n$  particles  $(n_i)_{i=1\dots n}$ , the inertial tensor  $\mathcal{I}^c$  in relation to the point P is (mathematical notation):

$$\mathcal{I}^c/P = \begin{bmatrix} \mathcal{I}_{xx}^c/P & -\mathcal{I}_{xy}^c/P & -\mathcal{I}_{xz}^c/P \\ -\mathcal{I}_{xy}^c/P & \mathcal{I}_{yy}^c/P & -\mathcal{I}_{yz}^c/P \\ -\mathcal{I}_{xz}^c/P & -\mathcal{I}_{yz}^c/P & \mathcal{I}_{zz}^c/P \end{bmatrix} \quad (8)$$

with:

$$\begin{aligned} \mathcal{I}_{xx}^c/P &= \sum_{i=1}^n m_i((y-y_p)_i^2 + (z-z_p)_i^2) & \mathcal{I}_{yz}^c/P &= \sum_{i=1}^n m_i(y-y_p)_i(z-z_p)_i \\ \mathcal{I}_{yy}^c/P &= \sum_{i=1}^n m_i((x-x_p)_i^2 + (z-z_p)_i^2) & \mathcal{I}_{xz}^c/P &= \sum_{i=1}^n m_i(x-x_p)_i(z-z_p)_i \\ \mathcal{I}_{zz}^c/P &= \sum_{i=1}^n m_i((x-x_p)_i^2 + (y-y_p)_i^2) & \mathcal{I}_{xy}^c/P &= \sum_{i=1}^n m_i(x-x_p)_i(y-y_p)_i \end{aligned}$$


---

## 2.2 Change-of-coordinate matrix from body trihedron to element trihedron

Let's define the following trihedron:

- $T_e = (\vec{x}_e, \vec{y}_e, \vec{z}_e)$  : trihedron for the element 'e'
- $T_c = (\vec{x}_c, \vec{y}_c, \vec{z}_c)$  : trihedron for the body 'c' containing element 'e'

From the trihedron  $T_c = (\vec{x}_c, \vec{y}_c, \vec{z}_c)$  to the trihedron  $T_e = (\vec{x}_e, \vec{y}_e, \vec{z}_e)$  we use the Euler angles ( $\psi$  around  $\vec{x}_c$ ,  $\theta$  around  $\vec{y}_1$  and  $\varphi$  around  $\vec{x}_e$ ).

The change-of-coordinate matrix  $P^{e \rightarrow c}$  for a vector of the trihedron  $T_e$  to the trihedron  $T_c$  is:

$$P^{e \rightarrow c} = \begin{bmatrix} \cos \theta & \sin \theta \sin \varphi & \sin \theta \cos \varphi \\ \sin \theta \sin \psi & \cos \varphi \cos \psi - \cos \theta \sin \varphi \sin \psi & -\sin \varphi \cos \psi - \cos \theta \cos \varphi \sin \psi \\ -\sin \theta \cos \psi & \cos \varphi \sin \psi + \cos \theta \sin \varphi \cos \psi & -\sin \varphi \sin \psi + \cos \theta \cos \varphi \cos \psi \end{bmatrix} \quad (9)$$