

In a nutshell: Approximating solutions to systems of higher-order initial value problems

Given a system of m initial-value problems (IVP) where the k^{th} IVP is an n_k -order IVP, then such a system can be converted into system of $n_1 + \dots + n_m$ 1st-order IVPs by generalizing the steps seen previously. This cannot be described mathematically without a lot of unnecessary notation, and thus, instead, we will give an example. Here is a system of two 2nd-order IVPs and a 3rd-order IVP.

$$\begin{aligned}
 x^{(2)}(t) &= f_1(t, x(t), x^{(1)}(t), y(t), y^{(1)}(t), z(t), z^{(1)}(t), z^{(2)}(t)) \\
 y^{(2)}(t) &= f_2(t, x(t), x^{(1)}(t), y(t), y^{(1)}(t), z(t), z^{(1)}(t), z^{(2)}(t)) \\
 z^{(3)}(t) &= f_3(t, x(t), x^{(1)}(t), y(t), y^{(1)}(t), z(t), z^{(1)}(t), z^{(2)}(t)) \\
 x(t_0) &= x_0 \\
 x^{(1)}(t_0) &= x_0^{(1)} \\
 y(t_0) &= y_0 \\
 y^{(1)}(t_0) &= y_0^{(1)} \\
 z(t_0) &= z_0 \\
 z^{(1)}(t_0) &= z_0^{(1)} \\
 z^{(2)}(t_0) &= z_0^{(2)}
 \end{aligned}$$

This can be written as the following system of seven IVPs:

$$\mathbf{w}(t) = \begin{pmatrix} w_1(t) \\ w_2(t) \\ w_3(t) \\ w_4(t) \\ w_5(t) \\ w_6(t) \\ w_7(t) \end{pmatrix} = \begin{pmatrix} x(t) \\ x^{(1)}(t) \\ y(t) \\ y^{(1)}(t) \\ z(t) \\ z^{(1)}(t) \\ z^{(2)}(t) \end{pmatrix}, \quad \mathbf{w}^{(1)}(t) = \mathbf{f}(t, \mathbf{w}(t)) = \begin{pmatrix} w_2(t) \\ f_1(t, w_1(t), \dots, w_7(t)) \\ w_4(t) \\ f_2(t, w_1(t), \dots, w_7(t)) \\ w_6(t) \\ w_7(t) \\ f_3(t, w_1(t), \dots, w_7(t)) \end{pmatrix}, \quad \text{and } \mathbf{w}(t_0) = \begin{pmatrix} x_0 \\ x_0^{(1)} \\ y_0 \\ y_0^{(1)} \\ z_0 \\ z_0^{(1)} \\ z_0^{(2)} \end{pmatrix} = \mathbf{w}_0.$$

where we index \mathbf{w} from 1 to 7 = 2 + 2 + 3. When we examine the approximation \mathbf{w}_k , the 1st entry approximates $x(t_k)$, the 3rd entry approximates $y(t_k)$, and the 5th entry approximates $z(t_k)$. The approximations of the 2nd, 4th, and 6th entries can be used for the derivatives with respect to the splines used to find intermediate values.