

DETERMINING A CONIC

In the affine euclidean space we fix the coordinate system $R=\{O, \{e_1, e_2\}\}$.

▼ **Determine the conic C with center Z(1/2,0) and going throught the points P(0,1), Q(1,1) .**

▼ **Method 1. With 5 points of the conic. Going also through M(1,0).**

```
> restart:with(linalg):
```

```
> A:=matrix([[a00,a01,a02],[a01,a11,a12],[a02,a12,a22]]);
```

$$A := \begin{bmatrix} a00 & a01 & a02 \\ a01 & a11 & a12 \\ a02 & a12 & a22 \end{bmatrix} \quad (1.1.1)$$

```
> P:=matrix(3,1,[1,0,1]);Q:=matrix(3,1,[1,1,1]):M:=matrix(3,1,[1,1,0]):
```

$$P := \begin{bmatrix} 1 \\ 0 \\ 1 \end{bmatrix} \quad (1.1.2)$$

```
> ecu1:=evalm(transpose(P)*A*P)[1,1];
      ecu1 := a00 + 2 a02 + a22
```

(1.1.3)

```
> ecu2:=evalm(transpose(Q)*A*Q)[1,1];
      ecu2 := a00 + 2 a01 + 2 a02 + a11 + 2 a12 + a22
```

(1.1.4)

```
> ecu3:=evalm(transpose(M)*A*M)[1,1];
      ecu3 := a00 + 2 a01 + a11
```

(1.1.5)

```
> Pp:=evalm(2*Z-P);Qp:=evalm(2*Z-Q);
```

$$Pp := \begin{bmatrix} 1 \\ 1 \\ -1 \end{bmatrix}$$

(1.1.6)

$$Qp := \begin{bmatrix} 1 \\ 0 \\ -1 \end{bmatrix} \quad (1.1.6)$$

```
> ecu4:=evalm(transpose(Pp)*A*Pp)[1,1];
      ecu4 := a00 + 2 a01 - 2 a02 + a11 - 2 a12 + a22
```

(1.1.7)

```
> ecu5:=evalm(transpose(Qp)*A*Qp)[1,1];
      ecu5 := a00 - 2 a02 + a22
```

(1.1.8)

```
> solve({ecu1,ecu2,ecu3,ecu4,ecu5,ecu6},{a00,a01,a02,a11,a12,
      a22});
      {a00=0, a01=a01, a02=0, a11=-2 a01, a12=0, a22=0}
```

(1.1.9)

Therefore the matrix of the conic is:

```
> AA:=matrix([[0,1,0],[1,-2,0],[0,0,0]]);
      AA := \begin{bmatrix} 0 & 1 & 0 \\ 1 & -2 & 0 \\ 0 & 0 & 0 \end{bmatrix}
```

(1.1.10)

```
> X:=matrix(3,1,[1,x,y]);
> CC:=simplify(evalm(transpose(X)*AA*X)[1,1]);
      CC := 2 x - 2 x^2
```

(1.1.11)

Which is a degenerate conic, two parallel lines $x=0$ and $x=1$ (it has a line of centers $x=1/2$).

▼ Method 2. With conic bundles. Going through the point T(-1,0).

```
> PZ:=det(matrix([[1,x,y],[1,0,1],[1,1/2,0]]));
      PZ := -\frac{1}{2} + \frac{1}{2} y + x
```

(1.2.1)

```
> QZ:=det(matrix([[1,x,y],[1,1,1],[1,1/2,0]]));
      QZ := -\frac{1}{2} - \frac{1}{2} y + x
```

(1.2.2)

```
> PQ:=det(matrix([[1,x,y],[1,0,1],[1,1,1]]));
      PQ := -1 + y
```

(1.2.3)

```
> Pp:=evalm(2*Z-P);Qp:=evalm(2*Z-Q);
      Pp := \begin{bmatrix} 1 \\ 1 \\ -1 \end{bmatrix}
      Qp := \begin{bmatrix} 1 \\ 0 \\ -1 \end{bmatrix}
```

(1.2.4)

```
> PpQp:=det(matrix([[1,x,y],[1,1,-1],[1,0,-1]]));
```

(1.2.5)

$$PpQp := -1 - y \quad (1.2.5)$$

```
> C1:=expand(PZ*QZ);
```

$$C1 := \frac{1}{4} - x - \frac{1}{4} y^2 + x^2 \quad (1.2.6)$$

```
> C2:=expand(PQ*PpQp);
```

$$C2 := 1 - y^2 \quad (1.2.7)$$

```
> H:=a*C1+b*C2;
```

$$H := a \left(\frac{1}{4} - x - \frac{1}{4} y^2 + x^2 \right) + b (1 - y^2) \quad (1.2.8)$$

```
> subs({x=-1,y=0},H)=0;
```

$$\frac{9}{4} a + b = 0 \quad (1.2.9)$$

```
> C:=-4/9*C1+C2;
```

$$C := \frac{8}{9} + \frac{4}{9} x - \frac{8}{9} y^2 - \frac{4}{9} x^2 \quad (1.2.10)$$

```
> with(plots):
```

```
> implicitplot(C,x=-3..3,y=-3..3);
```

