

Contents

PART I
THREE CLASSES OF PROBLEMS IN MATHEMATICS,
PHYSICS, AND ENGINEERING

Chapter 1. Simplest ill-posed problems	2
1.1. Statement of the problem. Examples	2
1.2. Definitions	6
1.3. Examples and approaches to solving ill-posed problems	7
1.4. Ill-posed problems of synthesis for optimum control systems . . .	13
1.5. Ill-posed problems on finding eigenvalues for systems of linear homogeneous equations	22
1.6. Solution of systems of differential equations. Do solutions always depend on parameters continuously?	25
1.7. Conclusions	33
 Chapter 2. Problems intermediate between well- and ill-posed problems	 35
2.1. The third class of problems in mathematics, physics and engineer- ing, and its significance	35
2.2. Transformations equivalent in the classical sense	36
2.3. Discovered paradoxes	39
2.4. Transformations equivalent in the widened sense	40
2.5. Problems intermediate between well- and ill-posed problems . . .	43
2.6. Applications to control systems and some other objects described by differential equations	48
2.7. Applications to practical computations	56
2.8. Conclusions from Chapters 1 and 2	62

Chapter 3. Change of sensitivity to measurement errors under integral transformations used in modeling of ships and marine control systems	64
3.1. Application of integral transformations to practical problems . . .	64
3.2. Properties of correlation functions	68
3.3. Properties of spectra	73
3.4. Correctness of integral transformations	77
3.5. Problems low sensitive to errors in the spectrum	80
3.6. Differentiation of distorted functions	86
3.7. Prognostication	92
Bibliography to Part I	102

PART II

STABLE METHODS FOR SOLVING INVERSE PROBLEMS

Chapter 4. Regular methods for solving ill-posed problems	107
4.1. Elements of functional analysis	107
4.2. Some facts from linear algebra	114
4.3. Basic types of equations and transformations	121
4.4. Well- and ill-posedness according to Hadamard	131
4.5. Classical methods for solving Fredholm integral equations of the first kind	143
4.6. Gauss least-squares method and Moore–Penrose inverse-matrix method	148
4.7. Tikhonov regularization method	155
4.8. Solution-on-the-compact method	176
Chapter 5. Inverse problems in image reconstruction and tomography	187
5.1. Reconstruction of blurred images	187
5.2. Reconstruction of defocused images	197
5.3. X-ray tomography problems	204
5.4. Magnetic-field synthesis in an NMR tomograph	213
Bibliography to Part II	225