

Figure 2.1
Sigmoid curve.

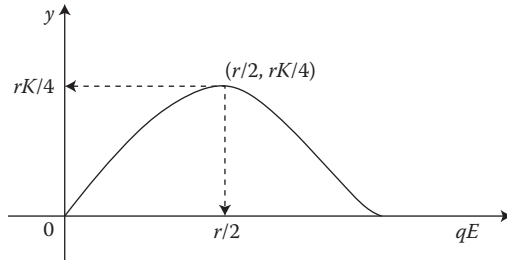


Figure 2.2

Yield curve. (From Kot, M. *Elements of Mathematical Ecology*. Cambridge University Press, Cambridge, UK, 2001. With permission.)

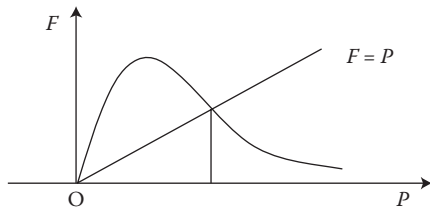


Figure 2.3
Population in nonoverlapping generations.

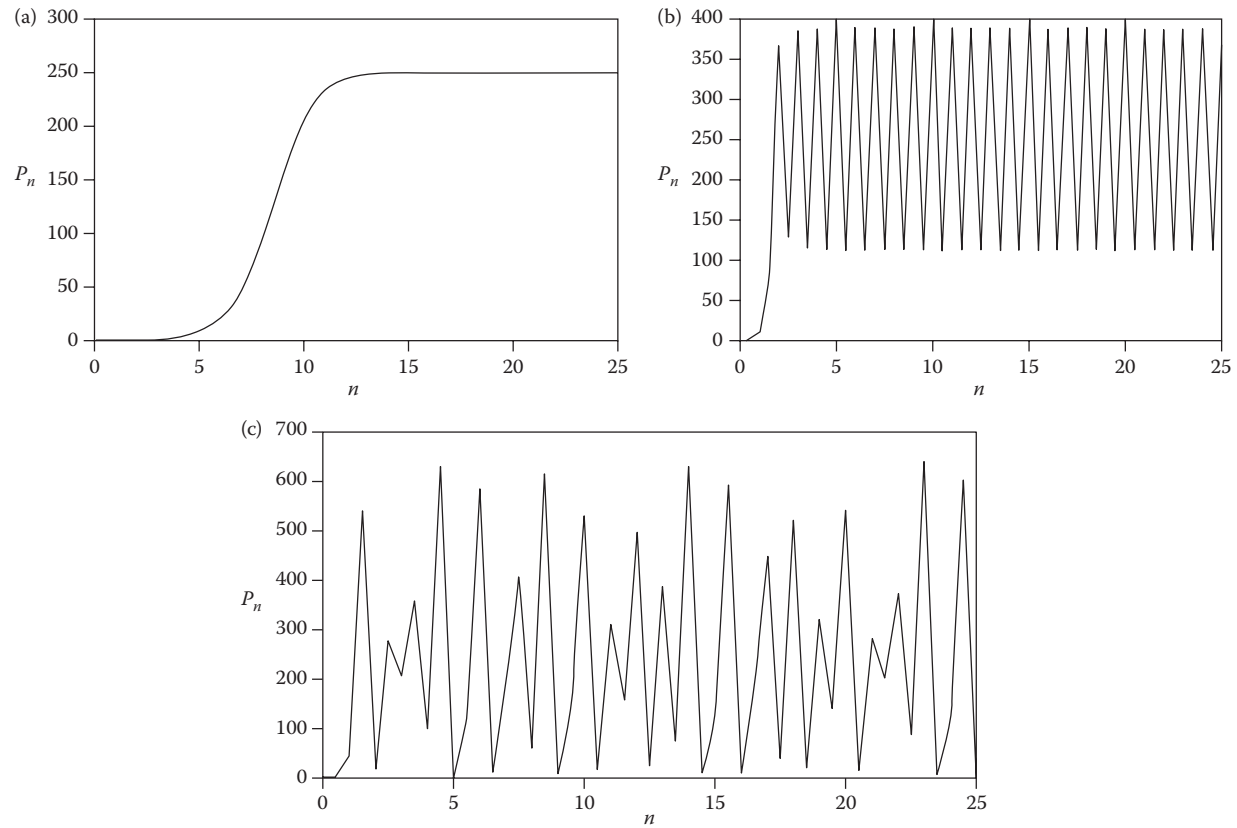


Figure 2.4
(a)–(c) Plots of population dynamics in Ricker model.

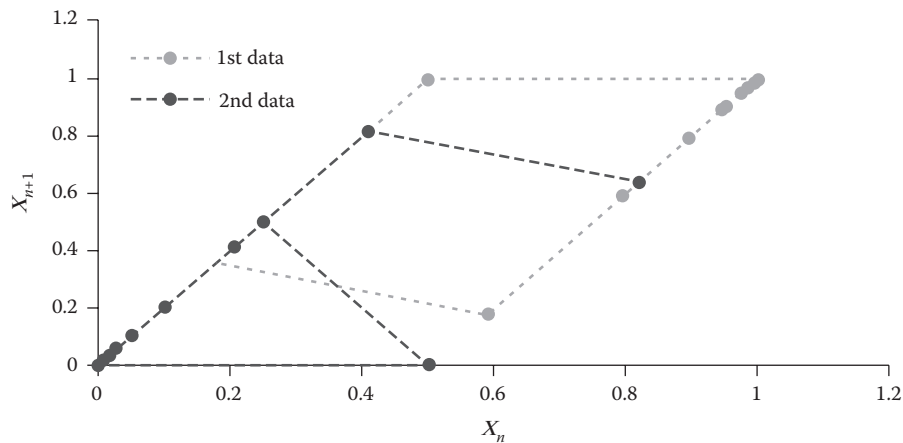


Figure 2.5

Map of Equation 2.33 for $k = 2$. First data are given in (i) and second data are given in (ii).

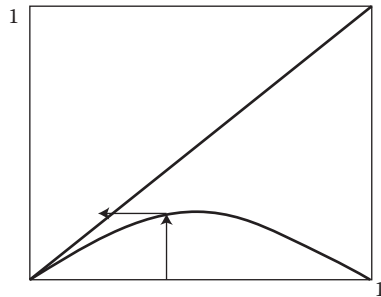


Figure 2.6
Stable equilibrium point. $A = 0.8$ (Not to scale.)

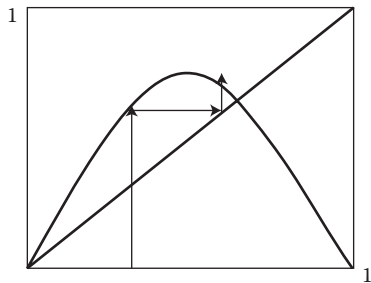


Figure 2.7
Stable equilibrium point. $A = 3.0$ (Not to scale.)

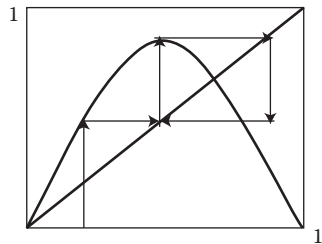


Figure 2.8
Stable equilibrium point. $A = 3.2$ (Not to scale.)



Figure 2.9

The design of the dress was based on the bifurcation diagram of the logistic map $x_{n+1} = ax_n(1 - x_n)$. (Courtesy Eri Matsui, Keiko Kimoto, and Kazuyuki Aihara [Kazuyuki Aihara, private communication].)

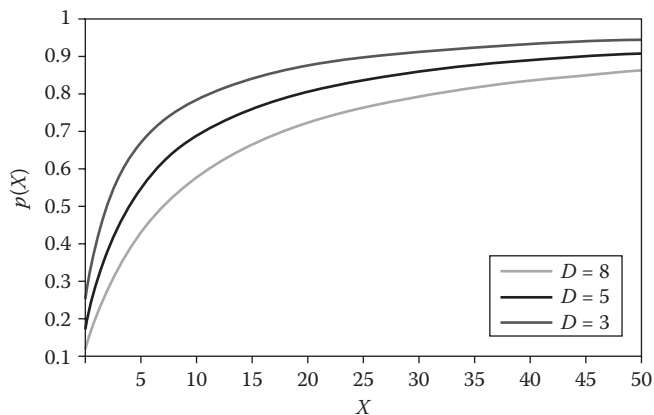


Figure 2.10
Holling type II functional response plotted for different values of $D = 3, 5$, and 8 .

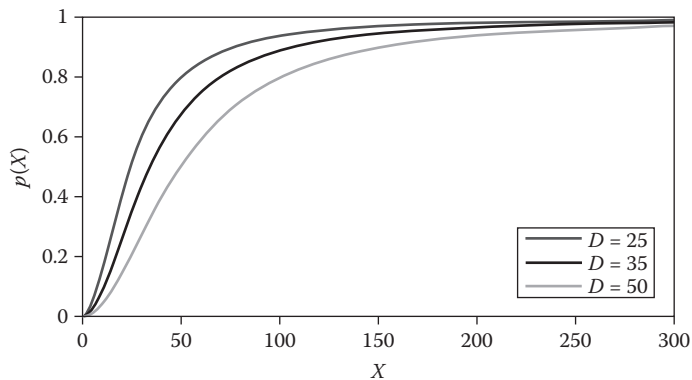


Figure 2.11
Holling type III functional response plotted for different values of D .

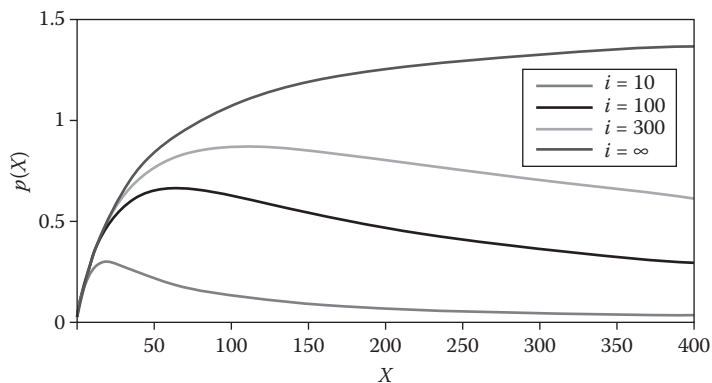


Figure 2.12
Holling type IV functional response plotted for fixed values of $c = 1.4$, $a = 40$ and different values of $i = 10, 100, 300$, and ∞ .

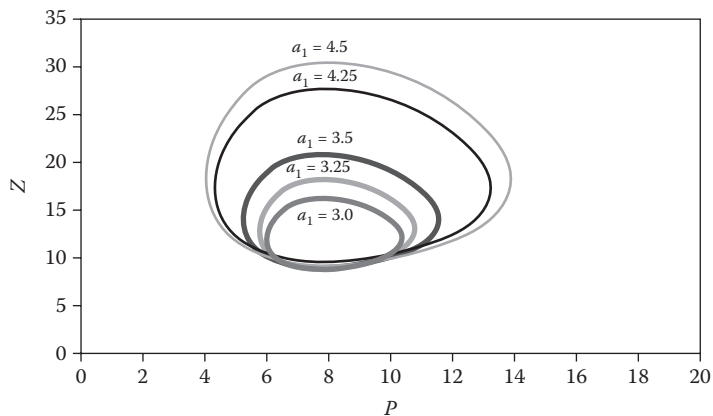


Figure 2.13
Closed (P, Z) phase plane trajectories for the LV model for different values of the parameter $a_1 = 4.5$, 4.25, 3.5, 3.25, and 3.0.

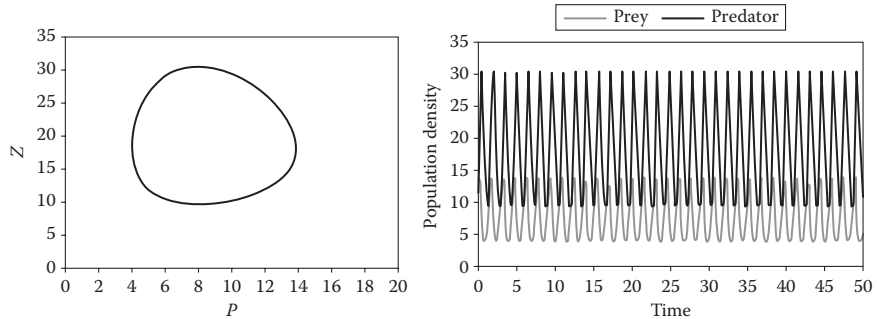


Figure 2.14
Phase plane trajectory and the corresponding time series for the LV model for the parameter values $a_1 = 4.5$, $b_1 = 0.25$, $a_2 = 4.0$, $b_2 = 0.5$.

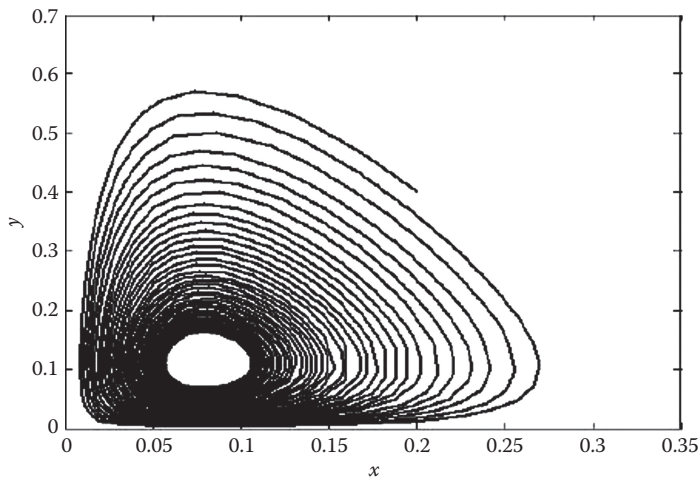


Figure 2.15
A limit cycle of system (2.56) for $a = 1$, $c = 3$, $d = 2$, $\alpha = 2$.

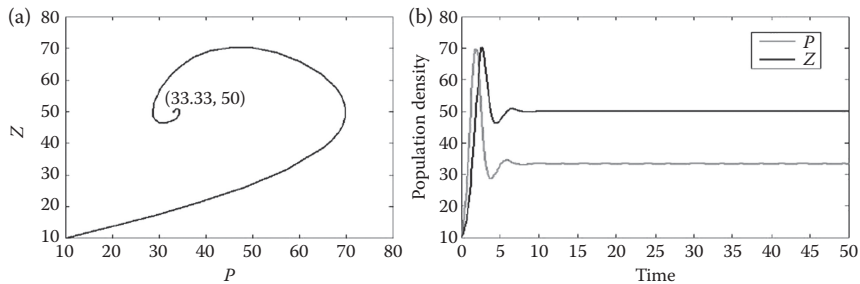


Figure 2.16
Stable focus: (a) Phase plot, (b) time series, for model (2.60).

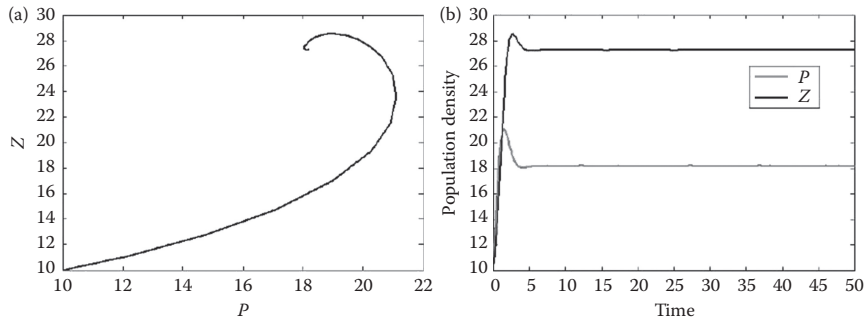


Figure 2.17
Stable focus: (a) Phase plot, (b) time series, for model (2.61).

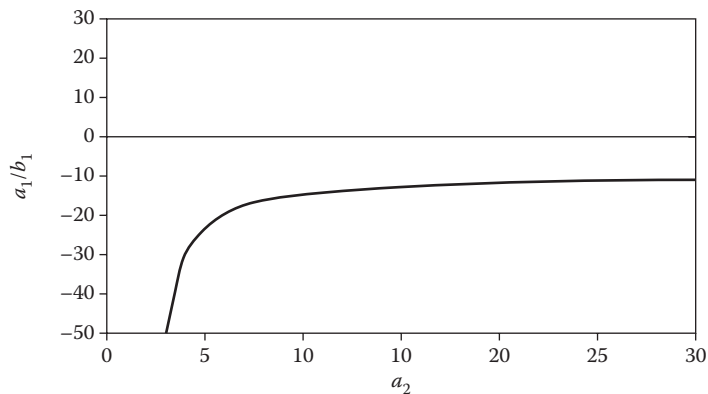


Figure 2.18
Plot of the bounding curve $xy = 2(y - 5x - 10)$.

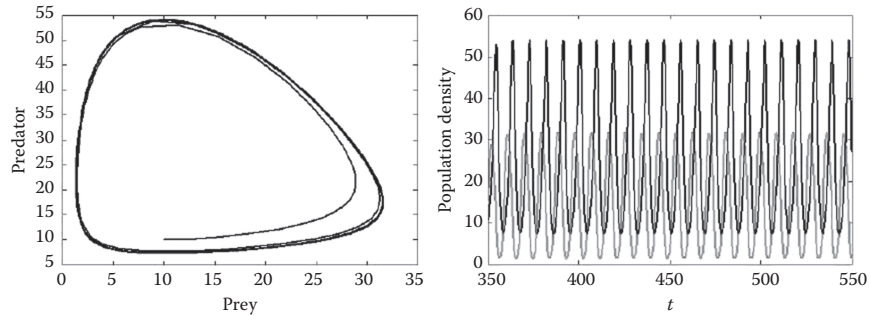


Figure 2.19
Phase plot and time-series displaying oscillatory dynamics in *RM* model (2.62) and (2.63).



Figure 2.20
Interactions incorporated in the model system.

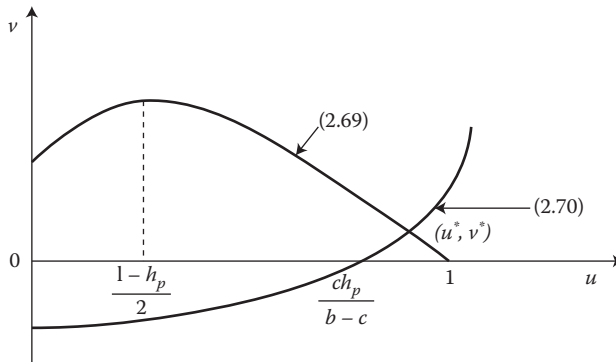


Figure 2.21

Equilibrium point $E^*(u^*, v^*)$ as the point of intersection of Equations 2.69 and 2.70. (From Dubey, B., Kumari, N., Upadhyay, R. K. 2009. *J. Appl. Math. Comput.* 31, 413–432. Copyright 2008, Springer. Reprinted with kind permission from Springer Science + Business Media B.V.)

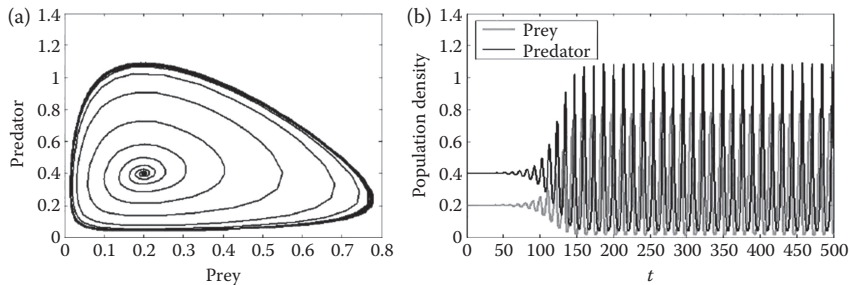


Figure 2.22

Limit-cycle solution: (a) Phase plot, (b) time series, for model (2.67) and (2.68).

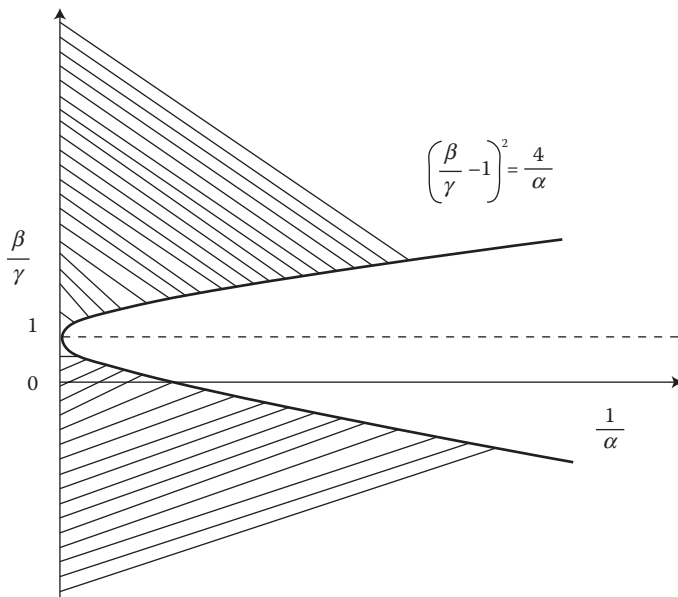


Figure 2.23

Shaded region which produces stable limit-cycle solutions. (From Upadhyay, R. K., Kumari, N., Rai, V. *Math. Model. Nat. Phenomena* 3, 71–95, 2008. With permission.)

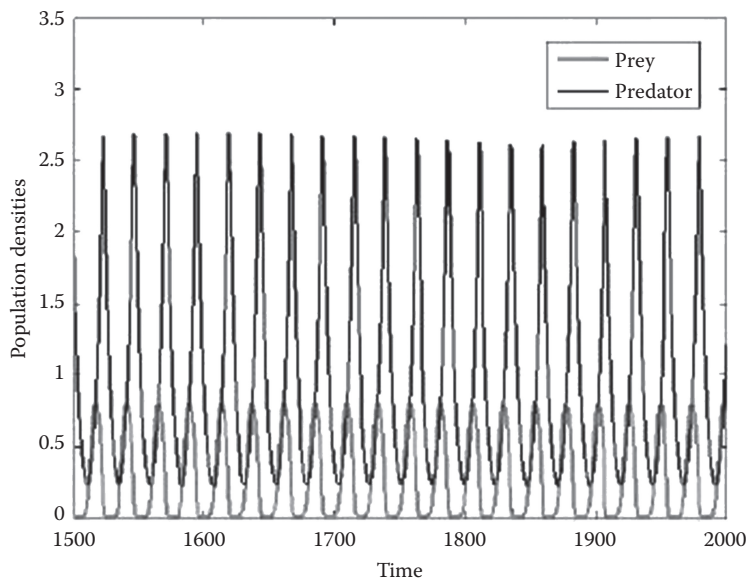


Figure 2.24
Time series displaying a limit cycle.

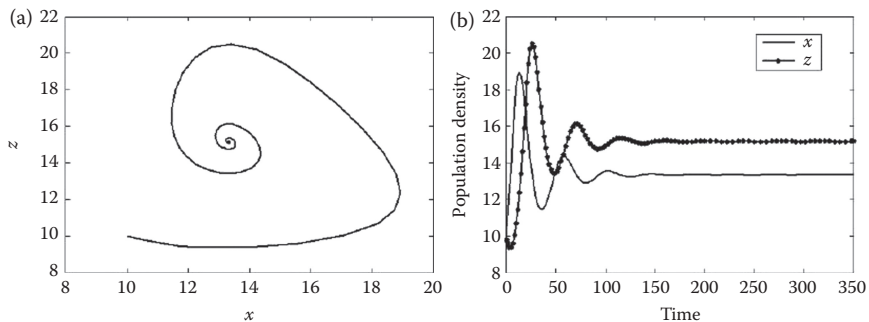


Figure 2.25
Stable focus: (a) Phase plot, (b) time series, for model (2.79) and (2.80).

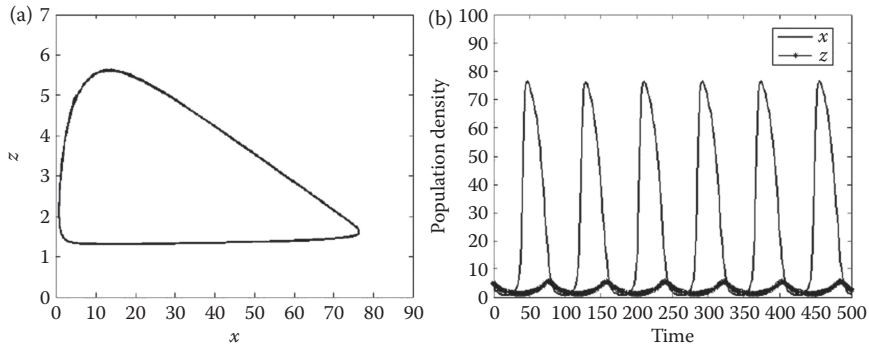


Figure 2.26
Limit-cycle solution. (a) Phase plot, (b) time series, for model (2.79) and (2.80).

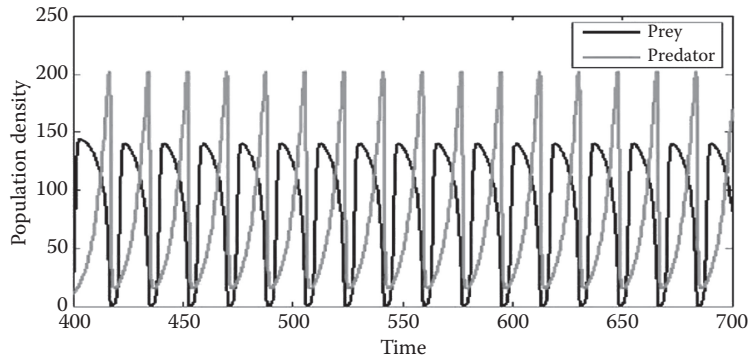


Figure 2.27
Oscillatory predator–prey dynamics exhibited by the HT model.

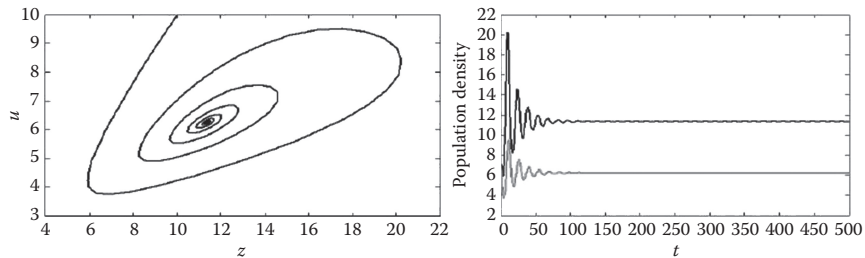


Figure 2.28

Phase plot and time series for the model system (2.90) and (2.91) for the given set of parameter values.



Figure 2.29

Fashion dress designed and created using model (2.112) and (2.113). (Courtesy Eri Matsui, Keiko Kimoto, and Kazuyuki Aihara. Fashion Show in Japan, 2010; Kazuyuki Aihara, private communication.)