Research Article

Bilinear Equation of the Nonlinear Partial Differential Equation and Its Application

Xiao-Feng Yang and Yi Wei

1College of Science, Northwest A&F University, Yangling, 712100 Shaanxi, China
2School of Medical Information Engineering, Jining Medical University, Rizhao 276826, China

Correspondence should be addressed to Xiao-Feng Yang; yangxiaofeng@nwafu.edu.cn

Received 4 March 2020; Accepted 6 April 2020; Published 28 April 2020

Academic Editor: Liguang Wang

The homogeneous balance of undetermined coefficient method is firstly proposed to derive a more general bilinear equation of the nonlinear partial differential equation (NLPDE). By applying perturbation method, subsidiary ordinary differential equation (sub-ODE) method, and compatible condition to bilinear equation, more exact solutions of NLPDE are obtained. The KdV equation, Burgers equation, Boussinesq equation, and Sawada-Kotera equation are chosen to illustrate the validity of our method. We find that the underlying relation among the \(\frac{G'}{G}\) -expansion method, Hirota’s method, and HB method is a bilinear equation. The proposed method is also a standard and computable method, which can be generalized to deal with other types of NLPDE.

1. Introduction

The nonlinear partial differential equation (NLPDE) is known to describe a wide variety of phenomena not only in physics but also in biology, chemistry, and several other fields [1–3]. The investigation of the exact solutions for NLPDE plays an important role on the study of nonlinear physical phenomena [4–9]. In recent years, many powerful methods are used to obtain the exact solutions of NLPDE, for example, the inverse scattering method [7], Bäcklund and Darboux transformation method [8], homotopy perturbation method [9], first integral method [10–12], variational iteration method [13, 14], sub-ODE method [15–17], Jacobi elliptic function method [18], tanh-sech method [19], \(\frac{G'}{G}\) -expansion method [20, 21], Hirota’s method [22–24], and homogeneous balance (HB) method [25–27].

As the direct methods, the \(\frac{G'}{G}\) -expansion method, Hirota’s method, and HB method are very effective for constructing the exact solutions of NLPDE. Exact traveling wave solutions, N-soliton solutions, and solitary wave solutions of some NLPDE are obtained by using the above three methods [20–30]. Fan improved the HB method to investigate the BT, Lax pairs, symmetries, and exact solutions for some NLPDE [31, 32]. He also showed that there are many links among the HB method, Weiss-Tabor-Carnevale method, and Clarkson-Kruskal method.

However, there is no unified direct method which can be used to deal with all types of NLPDE. And also, no literature is available to illustrate the underlying relations among the three direct methods.

In the present paper, by improving some key steps in the HB method [26], we propose a new method, HB of undetermined coefficient method, which can be used to derive the bilinear equation of NLPDE. Based on the bilinear equation, by applying the perturbation method, sub-ODE method, and compatible condition, more exact solutions of NLPDE are obtained. We illustrate the real meaning of balance numbers.

We show the underlying relations among the \(\frac{G'}{G}\) -expansion method, Hirota’s method, and HB method.

This paper is organized as follows: the HB of undetermined coefficient method is described in Section 2. In Sections 3 and 4, the KdV equation and Burgers equation are chosen as examples to illustrate the method, respectively. In Section 5, the bilinear equations of Boussinesq equation and Sawada-Kotera equation are derived, respectively. Some brief conclusions are given in Section 6.
2. Description of the HB of Undetermined Coefficient Method

Let us consider a general NLPDE, say, in two variables

\[ P(u, u_t, u_x, u_{xx}, u_{tt}, \cdots) = 0, \]  

where \( P \) is a polynomial function of its arguments and the subscripts denote the partial derivatives. The HB of undetermined coefficient method consists of three steps.

**Step 1.** Suppose that the solution of Equation (1) is of the form

\[ u = a_{mn}(\ln w)_{m,n} + \sum_{i,j=0}^{i+m,j=n} a_{ij}(\ln w)_{i,j} + a_{00}, \]  

where \( u = u(x,t), w = w(x,t), (\ln w)_{i,j} = \partial^{i+j}(\ln w(x,t))/\partial x^i \partial t^j, m, n \) (balance numbers), and \( a_{ij} \) (balance numbers) are constants to be determined later.

**Step 2.** Balancing the terms with (biases) \( 0 \) (balance coe\textsuperscript{c}ficients) are constants to be determined later. By balancing the highest nonlinear terms and the highest order partial derivative terms, balance numbers are obtained. Substituting Equation (2) into Equation (1) and balancing the terms with \( (w_x/w)^i(w_t/w)^j \) yield a set of algebraic equations for \( a_{ij} \) \( (i = 1, \cdots, m, j = 1, \cdots, n) \).

**Step 3.** Generally, in order to obtain the exact solutions of Equation (1), there are three methods to deal with the bilinear equation of Equation (1):

(i) Applying the perturbation method to the bilinear equation of Equation (1), N-soliton solution of Equation (1) can be obtained.

(ii) By using traveling wave transformations

\[ w(x,t) = w(\xi), \quad \xi = x - Vt, \]  

the bilinear equation of Equation (1) satisfies the following ODE:

\[ w'' + \lambda w' + \mu w = 0, \]  

where the prime denotes the derivation with respect to \( \xi \) and \( \lambda, \mu, \) and \( V \) are constants to be determined later.

Substituting Equations (3) and (4) into Equation (1), it is converted into the following equation:

\[ l_1 w^2 + l_2 w w' + l_3 w'^2 = 0, \]  

where \( l_1, l_2, \) and \( l_3 \) are polynomial functions of \( V, \lambda, \) and \( \mu. \)

Setting \( l_1 = l_2 = l_3 = 0 \) yields a set of algebraic equations for \( V, \lambda, \) and \( \mu. \) Solving the set of algebraic equations and using the solutions of Equation (4), \( w \) can be determined. Substituting \( w \) into Equation (2), the exact traveling wave solutions of Equation (1) are obtained.

(iii) By applying the compatible condition \( (w_x = w_{xx}) \) to the bilinear equation of Equation (1), it is reduced to an ODE. Solving the ODE, more exact solutions of Equation (1) can be obtained.

Next, we choose the KdV equation and Burgers equation to illustrate our method.

3. Application to the KdV Equation

Let us consider the celebrated KdV equation in the form

\[ u_t + uu_x + \delta u_{xxx} = 0, \]  

where \( \delta \) is a constant. Suppose that the solution of Equation (6) is of the form

\[ u = a_{mn}(\ln w)_{m,n} + \sum_{i,j=0}^{i+m,j=n} a_{ij}(\ln w)_{i,j} + a_{00}, \]  

where \( m, n \) (balance numbers) are constants to be determined later.

Balancing \( u_{xxx} \) and \( uu_x \) in Equation (6), it is required that \( m + 3 = 2m + 1 \) and \( n = 2n \). Then, Equation (7) can be written as

\[ u = a_{20}(\ln w)_{xx} + a_{10}(\ln w)_x + a_{00}. \]  

From Equation (8), one can calculate the following derivatives:

\[ u = a_{20} \left( \frac{w_{xx}}{w} - \frac{w_x^2}{w^2} \right) + a_{10} \frac{w_x}{w} + a_{00}, \]

\[ u_x = a_{20} \left( \frac{w_{xxx}}{w} - \frac{3w_{xx}w_x}{w^3} + \frac{2w_x^3}{w^3} \right) + a_{10} \left( \frac{w_{xx}}{w} - \frac{w_x^2}{w^2} \right), \]

\[ u_t = a_{20} \left( \frac{w_{xxt}}{w} - \frac{w_{xx}w_t + 2w_xw_{xt}}{w^3} + \frac{2w_x^2w_t}{w^3} \right) + a_{10} \left( \frac{w_{xt}}{w} - \frac{w_xw_t}{w^2} \right). \]
where \( a_{00} \) is an arbitrary constant. Substituting Equation (11) into Equation (6), we get
\[
12\delta(K_1 + K_2 + K_3) = 0, \tag{12}
\]
where
\[
K_1 = \frac{w_{xxt}}{w} - 2w_x w_{xt} + w_x w_t + 2w_{t2} w_t, \\
K_2 = a_{00} \left( \frac{w_{xxx}}{w} - \frac{3w_x w_{xx}}{w^2} + \frac{2w_{t3}}{w^3} \right), \\
K_3 = \delta \left( \frac{w_{xxxx}}{w} + \frac{2w_{xxx} w_{xx} - 5w_{x2} w_{x}}{w^2} + \frac{16w_{xxxx} w_{t3} - 6w_x w_{t1}^2}{w^3} \right).
\]

Simplifying Equation (12) and integrating once with respect to \( x \), we get
\[
\frac{\partial}{\partial x} \left( \frac{(w_x^3 - w_x w_t^2)}{w^2} + \delta \left( \frac{w_{xxxx}}{w} - 4w_x w_{xxx} + 3w_{xx}^2 \right) + a_{00} \left( w_{xx} w - w_x^2 \right) - C(t) w^2 \right) = 0. \tag{14}
\]

Equation (14) is identical to
\[
(w_x w - w_x w_t) + \delta \left( w_{xxxx} w - 4w_x w_{xxx} + 3w_{xx}^2 \right) + a_{00} \left( w_{xx} w - w_x^2 \right) - C(t) w^2 = 0, \tag{15}
\]
where \( C(t) \) is an arbitrary function of \( t \) and \( a_{00} \) is an arbitrary constant.

In particular, taking \( C(t) \) as zero in Equation (15), we get the bilinear equation of Equation (6) as follows:
\[
(w_x w - w_x w_t) + \delta \left( w_{xxxx} w - 4w_x w_{xxx} + 3w_{xx}^2 \right) + a_{00} \left( w_{xx} w - w_x^2 \right) = 0. \tag{16}
\]

Equation (16) can be written concisely in terms of \( D \)-operators as
\[
(D_x D_t + \delta D_x^4 + a_{00} D_x^2) w \cdot w = 0, \tag{17}
\]
where
\[
D_x^n D_t^m a \cdot b = (\partial_x - \partial_x')^n (\partial_t - \partial_t')^m a(x,t)b(x',t') \bigg|_{x=x',t=t'}.
\]

Remark 1. Applying Hirota’s method [22–24], the bilinear equation of Equation (6) can be written as
\[
(D_x D_t + \delta D_x^4 + a_{00} D_x^2) w \cdot w = 0. \tag{19}
\]

Equation (19) is obtained by setting \( a_{00} = 0 \) in Equation (17). Obviously, Equation (19) is a special case of Equation (17).

(i) Now, we apply the perturbation method to Equation (17) to derive \( N \)-soliton solution of Equation (6). Suppose that \( w \) can be expanded as follows:
\[
w = 1 + \varepsilon w_1 + \varepsilon^2 w_2 + \cdots + \varepsilon^N w_N + \cdots, \tag{20}
\]
where \( \varepsilon \) is a parameter and \( w_i = w_i(x, t) \) \((i = 1, 2, \cdots)\).

Substituting Equation (20) into Equation (17) and arranging it at each order of \( \varepsilon \), we get
\[
\varepsilon : D_x (D_t + a_{00} D_x + \delta D_x^2) (w_1 \cdot 1 + 1 \cdot w_1) = 0, \tag{21}
\]

\[
\varepsilon^2 : D_x (D_t + a_{00} D_x + \delta D_x^2) (w_2 \cdot 1 + w_1 \cdot w_1 + 1 \cdot w_2) = 0, \\
\varepsilon^3 : D_x (D_t + a_{00} D_x + \delta D_x^2) (w_3 \cdot 1 + w_1 \cdot w_2 \cdot w_1 \cdot w_1) = 0, \\
+ w_1 \cdot w_2 + w_1 \cdot w_3) = 0,
\]

\[
\cdots
\]
The order-$\epsilon$ equation can be rewritten as a linear differential equation for $w_1$ as follows:

$$\frac{\partial}{\partial x} \left( \frac{\partial}{\partial t} + a_{00} \frac{\partial}{\partial x} + \delta \frac{\partial^3}{\partial x^3} \right) w_1 = 0. \quad (22)$$

Solving Equation (22), we get

$$w_1 = e^{P_1 x - (a_{00} P_1 + \delta P_1)t}, \quad (23)$$

where $P_1$ is an arbitrary constant.

The coefficient of $e^t$ can be rearranged as follows:

$$2 \frac{\partial}{\partial x} \left( \frac{\partial}{\partial t} + a_{00} \frac{\partial}{\partial x} + \delta \frac{\partial^3}{\partial x^3} \right) w_2 = -D_\lambda (D_1 + a_{00} D_2 + \delta D_3^2) w_1 \cdot w_1. \quad (24)$$

Substituting Equation (23) into Equation (24), the right-hand side of Equation (24) equals zero. Therefore, we can choose

$$w_2 = 0. \quad (25)$$

Substituting Equations (23) and (25) into Equation (20), we get

$$w = 1 + e^{P_1 x - (a_{00} P_1 + \delta P_1)t} + e^{P_2 x - (a_{00} P_2 + \delta P_2)t}, \quad (26)$$

where $P_1, a_{00},$ and $\xi_0^i$ are arbitrary constants.

Substituting Equation (26) into Equation (11), 1-soliton solution of Equation (6) can be obtained. If we choose $w_1 = e^{P_1 x - (a_{00} P_1 + \delta P_1)t} + e^{P_2 x - (a_{00} P_2 + \delta P_2)t}$ in Equation (22), similar to the process of obtaining 1-soliton solution, we can get 2-soliton solution of Equation (6) as follows:

$$w = 1 + e^{\eta_1} + e^{\eta_2} + \frac{(P_1 - P_2)^2}{(P_1 - P_2)} e^{\eta_1 + \eta_2}, \quad (27)$$

where $\eta_1 = P_1 x - (a_{00} P_1 + \delta P_1)t + \xi_0^1$, $\eta_2 = P_2 x - (a_{00} P_2 + \delta P_2)t + \xi_0^2$, $P_i, \xi_0^i$ ($i = 1, 2$), and $a_{00}$ are arbitrary constants.

Substituting Equation (27) into Equation (11), 2-soliton solution of Equation (6) can be obtained. Similarly, we can get $N$-soliton solution of Equation (6).

Remark 2. Obviously, setting $a_{00} = 0$ in Equations (23) and (27), 1-soliton and 2-soliton solutions of Equation (6) are identical to Hirota’s results [22–24].

Remark 3. By using the properties of $D$-operators [22–24], a Bäcklund transformation of Equation (17) can be obtained as follows:

$$(D_l + (a_{00} + \alpha) D_x + \delta D_3^2) w^* \cdot w = 0,$$

$$(D_x^2 - \beta D_x - \alpha) w^* \cdot w = 0, \quad (28)$$

where $w^*$ and $w$ satisfy Equation (17) and $\alpha, \beta,$ and $a_{00}$ are arbitrary constants.

(ii) Now, we discuss Equation (16) by using the sub-ODE method.

Using transformations $w(x, t) = w(\xi)$, $\xi = x - Vt$, Equation (16) is reduced to

$$(a_{00} - V) \left( w'' - w^2 \right) + \delta \left( w''' - 4w'w'' + 3w'^2 \right) = 0, \quad (29)$$

where the prime denotes the derivation with respect to $\xi$ and $V$ is a constant to be determined later.

Noticing the bilinear property of Equation (16), suppose that $w$ satisfies the following ODE:

$$w'' + \lambda w' + \mu w = 0, \quad (30)$$

where $\lambda$ and $\mu$ are parameters.

Substituting Equation (30) into Equation (16), we get

$$l_1 w'^2 + l_2 w'^3 + l_3 w^2 = 0, \quad (31)$$

where

$$l_1 = \mu (V - a_{00} + \delta (4\mu - \lambda^2)), \quad l_2 = \lambda (V - a_{00} + \delta (4\mu - \lambda^2)), \quad l_3 = V - a_{00} + \delta (4\mu - \lambda^2). \quad (32)$$

Setting $l_1 = l_2 = l_3 = 0$ yields a set of algebraic equations for $V, \lambda$, and $\mu$. Solving this set of algebraic equations, we get

$$V = a_{00} + \delta (\lambda^2 - 4\mu), \quad (33)$$

where $\lambda, \mu,$ and $a_{00}$ are arbitrary constants.

Substituting Equation (30) into Equation (11), we get

$$u = 12\delta \left( \frac{w}{w} + \frac{\lambda}{2} \right)^2 + 3\delta (\lambda^2 - 4\mu) + a_{00}. \quad (34)$$

Substituting the general solutions of Equation (30) into Equation (34), we get three types of traveling wave solutions of Equation (6) as follows.

When $\lambda^2 - 4\mu > 0$,

$$u_1(x, t) = u_1(\xi) = -3\delta A \left( C_1 e^{(\sqrt{2}\lambda \xi)} - C_2 e^{-(\sqrt{2}\lambda \xi)} \right)^2$$

$$+ 3\delta A + a_{00}, \quad (35)$$
where

\[ A = \lambda^2 - 4\mu, \]
\[ V = a_{00} + A\delta, \]
\[ \xi = x - (a_{00} + A\delta)t, \]

and \( \lambda, \mu, C_1, C_2, \) and \( a_{00} \) are arbitrary constants.

Taking \( C_1 = C_3 + C_4 \) and \( C_2 = C_3 - C_4 \), Equation (35) can be rewritten as

\[ u_2(x, t) = u_2(\xi) = -3\delta A \left( C_3 \sinh \left( \frac{\sqrt{A}}{2} \xi + C_4 \cosh \left( \frac{\sqrt{A}}{2} \xi \right) \right) + 3\delta A + a_{00}, \] (37)

where \( C_3, C_4, \) and \( a_{00} \) are arbitrary constants and \( A, V, \) and \( \xi \) are given by Equation (36).

In particular, if \( |C_4/C_3| < 1 \), then Equation (37) is reduced to

\[ u_3(x, t) = u_3(\xi) = 3\delta A \text{sech}^2 \left( \frac{\sqrt{A}}{2} \xi + \xi_0 \right) + a_{00}, \] (38)

where \( C_3, C_4, \) and \( a_{00} \) are arbitrary constants and \( A, V, \) and \( \xi \) are given by Equation (36), \( \xi_0 = \text{arctanh} (C_4/C_3) \).

When \( \lambda^2 - 4\mu < 0 \),

\[ u_4(x, t) = u_4(\xi) = \frac{3\delta A}{C_1 \cos \left( \frac{\sqrt{-A}}{2} \xi + C_2 \sin \left( \frac{\sqrt{-A}}{2} \xi \right) \right) + 3\delta A + a_{00}, \] (39)

where \( C_1, C_2, \) and \( a_{00} \) are arbitrary constants and \( A, V, \) and \( \xi \) are given by Equation (36).

Obviously, Equation (39) can be written as

\[ u_5(x, t) = u_5(\xi) = 3\delta A \text{sec}^2 \left( \frac{\sqrt{-A}}{2} \xi + \xi_0 \right) + a_{00}, \] (40)

where \( C_1, C_2, \) and \( a_{00} \) are arbitrary constants and \( A, V, \) and \( \xi \) are given by Equation (36), \( \xi_0 = -\text{arctan} \left( C_2/C_1 \right) \).

When \( \lambda^2 - 4\mu = 0 \),

\[ u_6(x, t) = u_6(\xi) = -12\delta \left( \frac{C_2}{C_1 + C_2} \right)^2 + a_{00}, \] (41)

where \( V = a_{00}, \xi = x - a_{00}t, C_1, C_2, \) and \( a_{00} \) are arbitrary constants.

(iii) Now, we discuss Equation (16) from the compatible condition. Equation (16) can be written as

\[ \delta w_{xxxx} + w_{xx} + a_{00}w_{xx} \] \( w \) 
\[ + \left( \delta \frac{3w_{xx}^2 - 4w_{xxx}w_x}{w_x} - a_{00}w_x^2 - w_xw_x \right) = 0. \] (42)

Notice \( w_x \neq 0 \); otherwise, we can only get a trivial solution. Setting the second term of Equation (42) to zero and solving \( w \), yields

\[ w_t = \delta \frac{3w_{xx}^2 - 4w_{xxx}w_x}{w_x} - a_{00}w_x^2, \] (43)

Substituting Equation (43) into Equation (42), we get

\[ w_{xxxx} + \frac{w_{xx}^2 - 2w_xw_{xx}w_{xxx}}{w_x^2} = 0. \] (44)

Integrating Equation (44) once with respect to \( x \), we get

\[ w_{xxx} - w_{xx} = b(t), \] (45)

where \( b(t) \) is an arbitrary function of \( t \).

Using transformations \( Y = w_{xx} \) and \( X = w_x \), Equation (45) is reduced to

\[ \frac{dY}{dX} = \frac{2Y}{X} + 2b(t). \] (46)

Solving the above equation, we get

\[ Y = c(t)X^2 - 2b(t)X, \] (47)

namely,

\[ w_{xx} = \sqrt{c(t)w_x^2 - 2b(t)w_x}, \] (48)

where \( b(t) \) and \( c(t) \) are arbitrary functions of \( t \).

Case 1. When \( b(t) = c(t) = 0 \), from Equation (48), we get

\[ w = c_1(t)x + c_2(t), \] (49)

where \( c_1(t) \) and \( c_2(t) \) are arbitrary functions of \( t \).

Substituting the above equation into Equation (48), we get

\[ x \frac{dc_1(t)}{dt} + \frac{dc_2(t)}{dt} = -a_{00}c_1(t). \] (50)

Setting the coefficients of \( x^i(i = 0, 1) \) to zero in the above equation, we get
\[
\begin{align*}
\frac{dc_1(t)}{dt} &= 0, \\
\frac{dc_2(t)}{dt} &= -a_{00}c_1(t).
\end{align*}
\] (51)

Solving the above equations, we get
\[
c_1(t) = C_1, \\
c_2(t) = C_2 - a_{00}C_1 t,
\] (52)

where \(C_i (i = 1, 2)\) are arbitrary constants. Then, we get
\[
w = C_i (x - a_{00} t) + C_2.
\] (53)

Substituting Equation (53) into Equation (11), we get an exact solution of Equation (6) as follows:
\[
u_8(x, t) = a_{00} - \frac{128C_i^2}{(C_1(x - a_{00} t) + C_2)^2},
\] (54)

where \(C_i (i = 1, 2)\) and \(a_{00}\) are arbitrary constants.

Case 2. When \(b(t) = 0\) and \(c(t) > 0\), similar to Case 1, we get
\[
w = C_3 + C_2 e^{C_1 (x - (a_{00} + \delta C_i) t)},
\] (55)

and an exact solution of Equation (6) as follows:
\[
u_8(x, t) = \frac{128C_i^2 C_2 e^{C_1 (x - (a_{00} + \delta C_i) t)}}{(C_1 + C_2 e^{C_1 (x - (a_{00} + \delta C_i) t)})^2} + a_{00},
\] (56)

where \(C_i (i = 1, 2, 3)\) and \(a_{00}\) are arbitrary constants.

Case 3. When \(b(t) \neq 0\) and \(c(t) = 0\) similar to Case 1, we get
\[
w = C_i (x - a_{00} t + C_2)^3 + 12\delta C_i t + C_3,
\] (57)

and an exact solution of Equation (6) as follows:
\[
u_9(x, t) = a_{00} - \frac{36\delta C_i (x - a_{00} t + C_2) (C_1(x - a_{00} t + C_2)^3 - 24\delta C_i t - 2C_3)}{(C_1(x - a_{00} t + C_2)^3 - 12\delta C_i t + C_3)^2},
\] (58)

where \(C_i (i = 1, 2, 3)\) and \(a_{00}\) are arbitrary constants.

Case 4. When \(b(t) \neq 0\) and \(c(t) > 0\), similar to Case 1, we get
\[
w = C_4 e^{C_1 (x - (a_{00} + \delta C_i) t)} + C_2 e^{-C_1 (x - (a_{00} + \delta C_i) t)}
\]
\[+ C_2 x - C_2 (a_{00} + 3\delta C_i^2) t + C_5,
\] (59)

where
\[
A_1 = \frac{C_1^2 C_4 e^{C_1 (x - (a_{00} + \delta C_i) t)} + C_1^2 C_5 e^{-C_1 (x - (a_{00} + \delta C_i) t)}}{C_4 e^{C_1 (x - (a_{00} + \delta C_i) t)} + C_3 e^{-C_1 (x - (a_{00} + \delta C_i) t)} + C_2 x - C_2 (a_{00} + 3\delta C_i) t + C_5},
\]
\[
B_1 = \left( \frac{C_1 C_4 e^{C_1 (x - (a_{00} + \delta C_i) t)} - C_1 C_3 e^{-C_1 (x - (a_{00} + \delta C_i) t)} + C_2}{C_4 e^{C_1 (x - (a_{00} + \delta C_i) t)} + C_3 e^{-C_1 (x - (a_{00} + \delta C_i) t)} + C_2 x - C_2 (a_{00} + 3\delta C_i) t + C_5} \right)^2.
\] (61)

where \(C_i (i = 1, 2, 3, 4, 5)\), and \(a_{00}\) are arbitrary constants.

Case 5. When \(b(t) \neq 0\) and \(c(t) < 0\), similar to Case 1, we get
\[
w = -\frac{C_1 C_2 x + C_1 \cos \left( C_2 (x + \delta C_2^2 t - a_{00} t + C_3) \right) + 3\delta C_1 C_2^2 t - a_{00} C_1 C_2 t - C_4 C_2^2}{C_2^3},
\] (62)
and an exact solution of Equation (6) as follows:

$$u_{11}(x, t) = 12\delta(A_2 - B_2) + a_{00}, \quad (63)$$

where

$$A_2 = \frac{-C_1 C_3^2 \cos \left( C_2 \left( x + \delta C_2^2 t - a_{00} t + C_3 \right) \right)}{C_1 C_2 x + C_1 \cos \left( C_2 \left( x + \delta C_2^2 t - a_{00} t + C_3 \right) \right) + 3\delta C_1 C_2^2 t - C_1 C_2 a_{00} t - C_2^2 C_4},$$

$$B_2 = \frac{C_2^2 C_3^2 \left( -1 + \sin \left( C_2 \left( x + \delta C_2^2 t - a_{00} t + C_3 \right) \right) \right)^2}{(C_1 C_2 x + C_1 \cos \left( C_2 \left( x + \delta C_2^2 t - a_{00} t + C_3 \right) \right) + 3\delta C_1 C_2^2 t - a_{00} C_1 C_2 t - C_2^2 C_4)^2}, \quad (64)$$

where $C_i$ ($i = 1, 2, 3, 4$) and $a_{00}$ are arbitrary constants.

So far, based on the bilinear equation which is derived by using the HB of undetermined coefficient method, many exact solutions of the KdV are obtained by applying the perturbation method, sub-ODE method, and compatible condition. Our results can compare with the $(G'/G)$-expansion method, Hirota’s results, and HB method [20–30].

4. Application to the Burgers Equation

Let us consider the Burgers equation in the form

$$u_t + uu_x + \delta u_{xx} = 0, \quad (65)$$

where $\delta$ is a constant.

Suppose that the solution of Equation (65) is of the form

$$u = a_{mn} \ln w \bigg|_{m,n} + \sum_{i,j=0 \atop i+j \neq m,n} a_{ij} \ln w_{ij} + a_{00}, \quad (66)$$

where $m, n$, and $a_{ij}$ ($i = 0, 1, \cdots, m, j = 0, 1, \cdots, n$) are constants to be determined later.

Balancing $u_{xx}$ and $uu_x$ in Equation (65), it is required that $m + 2 = 2m + 1$ and $n = 2n$. Then, Equation (66) can be written as

$$u = a_{10} \ln w \bigg|_x + a_{00}. \quad (67)$$

From Equation (67), one can calculate the following derivatives:

$$u = a_{10} \frac{w_{x}}{w} + a_{00},$$

$$u_x = a_{10} \left( \frac{w_{xx}}{w} - \frac{w_x^2}{w^2} \right),$$

$$u_t = a_{10} \left( \frac{w_{xt}}{w} - \frac{w_t w_x}{w^2} \right),$$

$$u_{xx} = a_{10} \left( \frac{w_{xxx}}{w} - 3 \frac{w_{x} w_{xx}}{w^2} + \frac{2w_{xxx}}{w^2} \right). \quad (68)$$

Equating the coefficients of $(w_{x}/w)^2$ on the left-hand side of Equation (65) to zero yields an algebraic equation for $a_{10}$ as follows:

$$-a_{10}^2 + 2a_{10} \delta = 0. \quad (69)$$

Solving the above algebraic equation, we get $a_{10} = 2\delta$. Substituting $a_{10}$ back into Equation (67), we get

$$u = 2\delta \ln w \bigg|_x + a_{00}, \quad (70)$$

where $a_{00}$ is an arbitrary constant.

Substituting Equation (70) into Equation (65), we get

$$2\delta(K_1 + K_2 + K_3) = 0, \quad (71)$$

where

$$K_1 = \frac{w_{xt} w - w_{x} w_t}{w^2},$$

$$K_2 = a_{00} \left( \frac{w_{xx} w - w_x^2}{w^2} \right),$$

$$K_3 = a_{00} \left( \frac{w_{xxx} w - w_{x} w_{xx}}{w^2} \right).$$

Simplifying Equation (71), we get

$$\left( w_{xt} w - w_{x} w_t \right) + a_{00} \left( w_{xx} w - w_x^2 \right) + 2\delta (w_{xxx} w - w_{x} w_{xx}) = 0. \quad (73)$$

Equation (73) can be written concisely in terms of $D$-operators as

$$D_x(w_t + \delta w_{xx} + a_{00} w_x) \cdot w = 0. \quad (74)$$

Equation (74) is identical to

$$w_t + \delta w_{xx} + a_{00} w_x - C(t) w = 0, \quad (75)$$

where $C(t)$ is an arbitrary function of $t$ and $a_{00}$ is an arbitrary constant.
In particular, taking \( C(t) \) as constant \( C \) in Equation (75), we get
\[
 w_t + \delta w_{xx} + a_{00}w_x - Cw = 0. \tag{76}
\]

**Remark 4.** Applying Hirota’s method [22–24], the bilinear equation of Equation (74) can be written as
\[
 D_x(w_t + \delta w_{xx}) = 0. \tag{77}
\]
Equation (77) is obtained by setting \( a_{00} = 0 \) in Equation (74). Obviously, Equation (77) is a special case of Equation (74).

**Remark 5.** Equations (70) and (76) are general Cole-Hopf transformations. In fact, setting \( a_{00} = C = 0 \) in Equations (70) and (76), we get the famous Cole-Hopf transformations
\[
 u = 2\delta \ln(w), w_t + \delta w_{xx} = 0. \tag{78}
\]

(i) Now, we apply the perturbation method to Equation (74) to derive \( N \)-soliton solution of Equation (65). Suppose that \( w \) can be expanded as follows:
\[
 w = 1 + \epsilon w_1 + \epsilon^2 w_2 + \cdots + \epsilon^N w_N + \cdots, \tag{79}
\]
where \( \epsilon \) is a parameter and \( w_i = w_i(x,t) \) \((i = 1,2,\cdots)\).

Substituting Equation (79) into Equation (74) and arranging it at each order of \( \epsilon \), we get
\[
 \epsilon: \frac{1}{2} \left( D_x + a_{00}D_t^2 \right) (w_1 \cdot 1 + 1 \cdot w_1) + \delta D_xw_{1xx} = 0, \tag{80}
\]
\[
 \epsilon^2: \frac{1}{2} \left( D_x + a_{00}D_t^2 \right) (w_2 \cdot 1 + w_1 \cdot w_1 + 1 \cdot w_2) + \delta D_x(w_1xx \cdot w_1 + w_2xx \cdot 1) = 0, \tag{81}
\]
\[
 \epsilon^3: \frac{1}{2} \left( D_x + a_{00}D_t^2 \right) (w_3 \cdot 1 + w_2 \cdot w_1 + w_1 \cdot w_2 + 1 \cdot w_3) + \delta D_x(w_1xx \cdot w_2 + w_2xx \cdot w_1 + w_3xx \cdot 1) = 0, \tag{82}
\]
\[\vdots\]

The order-\( \epsilon \) equation can be rewritten as a linear differential equation for \( w_1 \) as follows:
\[
 \frac{\partial}{\partial x} \left( \frac{\partial}{\partial t} + a_{00} \frac{\partial}{\partial x} + \delta \frac{\partial^2}{\partial x^2} \right) w_1 = 0. \tag{83}
\]
Solving Equation (81), we get
\[
 w_1 = e^{P_1 x - (a_{00} P_1 + \delta P_1^2)t}, \tag{84}
\]
where \( P_1 \) is an arbitrary constant.

The coefficient of \( \epsilon^2 \) can be rearranged as follows:
\[
 \frac{\partial}{\partial x} \left( \frac{\partial}{\partial t} + a_{00} \frac{\partial}{\partial x} + \delta \frac{\partial^2}{\partial x^2} \right) w_2 = \epsilon^2 \left( \frac{\partial}{\partial t} + a_{00} \frac{\partial}{\partial x} + \delta \frac{\partial^2}{\partial x^2} \right) w_1 \tag{85}
\]
Substituting Equation (82) into Equation (83), the right-hand side of Equation (83) equals zero. Therefore, we can choose
\[
 w_2 = 0. \tag{86}
\]
Substituting Equations (82) and (84) into Equation (79), we get
\[
 w = 1 + \epsilon P_2 x - (a_{00} P_2 + \delta P_2^2)t + \epsilon^2 P_2 x - (a_{00} P_2 + \delta P_2^2)t + \epsilon^3 P_2 x - (a_{00} P_2 + \delta P_2^2)t \tag{87}
\]
where \( P_1, a_{00} \), and \( \xi_1 \) are arbitrary constants.

Substituting Equation (85) into Equation (70), 1-soliton solution of Equation (65) can be obtained.

If we choose \( w_1 = e^{P_1 x - (a_{00} P_1 + \delta P_1^2)t} + e^{P_2 x - (a_{00} P_2 + \delta P_2^2)t} \) in Equation (81), Equation (74) has no 2-soliton solution. But there exists a solution as follows:
\[
 w = 1 + \sum_{i=1}^n e^{\eta_i t}, \tag{88}
\]
where \( \eta_i = P_i x - (a_{00} P_i + \delta P_i^2)t + \xi_i \) \((i = 1,2,\cdots,n)\), and \( a_{00} \) are arbitrary constants.

(ii) Now, we discuss Equation (73) by using the sub-ODE method.

Using transformations \( w(x,t) = w(\xi) \), \( \xi = x - Vt \), Equation (73) is reduced to
\[
 (a_{00} - V) \left( w'' w - w_{tt} \right) + \delta \left( w w'' - w' w'' \right) = 0, \tag{89}
\]
where the prime denotes the derivation with respect to \( \xi \) and \( V \) is a constant to be determined later.

Noticing the bilinear property of Equation (87), suppose that \( w \) satisfies the following ODE:
\[
 w'' + \lambda w' + \mu w = 0, \tag{90}
\]
where \( \lambda \) and \( \mu \) are parameters.

Substituting Equation (88) into Equation (87), we get
\[
 l_1 w^2 + l_2 w w' + l_3 w'^2 = 0, \tag{91}
\]
where

\[
\begin{align*}
l_1 &= \mu(\delta \lambda + V - a_{00}), \\
l_2 &= \lambda(\delta \lambda + V - a_{00}), \\
l_3 &= \delta \lambda + V - a_{00}.
\end{align*}
\]

(90)

Setting \( l_1 = l_2 = l_3 = 0 \) yields a set of algebraic equations for \( V, \lambda, \) and \( \mu \). Solving the set of algebraic equations, we get

\[
V = a_{00} - \delta \lambda,
\]

(91)

where \( \lambda, \mu, \) and \( a_{00} \) are arbitrary constants.

Substituting the general solutions of Equation (88) into Equation (70), we get three types of traveling wave solutions of Equation (65) as follows.

When \( \lambda^2 - 4\mu > 0 \),

\[
u_1(x, t) = u_1(\xi) = \delta \sqrt{\Delta} \left( \frac{C_1 e^{(\sqrt{\Delta})\xi} - C_2 e^{-(\sqrt{\Delta})\xi}}{C_1 e^{(\sqrt{\Delta})\xi} + C_2 e^{-(\sqrt{\Delta})\xi}} \right) + a_{00} - \delta \lambda,
\]

(92)

where

\[
\begin{align*}
\Delta &= \lambda^2 - 4\mu, \\
V &= a_{00} - \delta \lambda, \\
\xi &= x - (a_{00} - \delta \lambda)t,
\end{align*}
\]

(93)

where \( C_1, C_2, \lambda, \mu, \) and \( a_{00} \) are arbitrary constants.

Taking \( C_1 = (C_3 + C_4)/2 \) and \( C_2 = (C_3 - C_4)/2 \), Equation (93) can be written as

\[
u_2(x, t) = u_2(\xi) = \delta \sqrt{\Delta} \left( \frac{C_3 e^{(\sqrt{\Delta})\xi} + C_4 e^{-(\sqrt{\Delta})\xi}}{C_3 e^{(\sqrt{\Delta})\xi} + C_4 e^{-(\sqrt{\Delta})\xi}} \right) + a_{00} - \delta \lambda,
\]

(94)

where \( C_3, C_4, \) and \( a_{00} \) are arbitrary constants and \( A \) and \( \xi \) are given by Equation (94).

In particular, if \(|C_4/C_3| < 1\), then Equation (94) is reduced to

\[
u_3(x, t) = u_3(\xi) = \delta \sqrt{\Delta} \tanh \left( \frac{\sqrt{\Delta}}{2} \xi + \xi_0 \right) + a_{00} - \delta \lambda,
\]

(95)

where \( C_3, C_4, \) and \( a_{00} \) are arbitrary constants and \( A \) and \( \xi \) are given by Equation (94), \( \xi_0 = \text{arctanh} \left( C_4/C_3 \right) \).

When \( \lambda^2 - 4\mu < 0 \),

\[
u_4(x, t) = u_4(\xi) = \delta \sqrt{-\Delta} \left( \frac{-C_3 \sin \left( \frac{\sqrt{-\Delta}}{2} \xi \right) + C_4 \cos \left( \frac{\sqrt{-\Delta}}{2} \xi \right)}{C_3 \cos \left( \frac{\sqrt{-\Delta}}{2} \xi \right) + C_4 \sin \left( \frac{\sqrt{-\Delta}}{2} \xi \right)} \right) + a_{00} - \delta \lambda,
\]

(96)

where \( C_3, C_4, \) and \( a_{00} \) are arbitrary constants and \( A \) and \( \xi \) are given by Equation (94).

Obviously, Equation (96) can be written as

\[
u_5(x, t) = u_5(\xi) = -\delta \sqrt{-A} \tan \left( \frac{\sqrt{-A}}{2} \xi - \xi_0 \right) + a_{00} - \delta \lambda,
\]

(97)

where \( \lambda, \mu, \) and \( a_{00} \) are arbitrary constants and \( A \) and \( \xi \) are given by Equation (94), \( \xi_0 = \arctan \left( C_4/C_3 \right) \).

When \( \lambda^2 - 4\mu = 0 \),

\[
u_6(x, t) = u_6(\xi) = \frac{2\delta C^2}{C_1 + C_2\xi} + a_{00} - \delta \lambda,
\]

(98)

where \( \xi = x - (a_{00} - \delta \lambda)t, C_1, C_2, \lambda, \mu, \) and \( a_{00} \) are arbitrary constants.

(iii) Now, we discuss Equation (73) from the compatible condition.

Using the compatible condition, we can get nothing but Equation (76). Using transformations \( w(x, t) = w(\xi), \xi = x - Vt \), Equation (76) is reduced to

\[
dw'' + (a_{00} - V)w' - Cw = 0.
\]

(99)

Substituting the general solutions of Equation (99) into Equation (70), we get three types of traveling wave solutions of Equation (65) as follows.

When \((a_{00} - V)^2 > 4C\delta > 0\),

\[
u_7(x, t) = u_7(\xi) = \sqrt{\Delta} \left( \frac{C_1 e^{(\sqrt{\Delta})\xi} - C_2 e^{-(\sqrt{\Delta})\xi}}{C_1 e^{(\sqrt{\Delta})\xi} + C_2 e^{-(\sqrt{\Delta})\xi}} \right) + V_1,
\]

(100)

where

\[
\Delta = (a_{00} - V)^2 + 4C\delta,
\]

(101)

\[
\xi = x - V_1 t,
\]

where \( V_1, C_1, C_2, \) and \( a_{00} \) are arbitrary constants.
Taking \( C_1 = (C_3 + C_4)/2 \) and \( C_2 = (C_3 + C_4)/2 \), Equation (101) can be written as

\[
\begin{align*}
\alpha_8(x, t) &= \alpha_8(\xi) = \sqrt{\Delta} \\
&\times \left( C_3 \sinh \left( \frac{\sqrt{\Delta}/2\xi + C_4 \cosh \left( \frac{\sqrt{\Delta}/2\xi} \right) }{C_3 \cosh \left( \frac{\sqrt{\Delta}/2\xi} \right) + C_4 \sinh \left( \frac{\sqrt{\Delta}/2\xi} \right) } \right) \\
&+ V_1, 
\end{align*}
\]

where \( V_1, C, C_3, C_4, \) and \( a_{00} \) are arbitrary constants and \( \Delta \) and \( \xi \) are given by Equation (101).

In particular, if \( C_3/C < 1 \), then Equation (102) is reduced to

\[
\begin{align*}
\alpha_9(x, t) &= \alpha_9(\xi) = \sqrt{\Delta} \tanh \left( \frac{\sqrt{\Delta}/2\xi + \xi_0} \right) + V_1, 
\end{align*}
\]

where \( \xi_0 = \text{arctanh} \left( C_3/C_3 \right) \), \( V_1, C, C_3, C_4, \) and \( a_{00} \) are arbitrary constants and \( \Delta \) and \( \xi \) are given by Equation (101).

When \( (a_{00} - V_2)^2 + 4C_\Delta < 0 \),

\[
\begin{align*}
\alpha_{10}(x, t) &= \alpha_{10}(\xi) = \sqrt{\Delta} \\
&\times \left( -C_3 \sin \left( \frac{\sqrt{\Delta}/2\xi + C_4 \cosh \left( \frac{\sqrt{\Delta}/2\xi} \right) }{C_3 \cosh \left( \frac{\sqrt{\Delta}/2\xi} \right) + C_4 \sinh \left( \frac{\sqrt{\Delta}/2\xi} \right) } \right) \\
&+ V_2, 
\end{align*}
\]

where \( V_2, C, C_3, C_4, \) and \( a_{00} \) are arbitrary constants and \( \Delta \) and \( \xi \) are given by Equation (101).

Obviously, Equation (104) can be written as

\[
\begin{align*}
\alpha_{11}(x, t) &= \alpha_{11}(\xi) = -\sqrt{\Delta} \tan \left( \frac{\sqrt{\Delta}/2\xi - \xi_0} \right) + V_2, 
\end{align*}
\]

where \( \xi_0 = -\arctan \left( C_4/C_3 \right) \), \( V_2, C, C_3, C_4, \) and \( a_{00} \) are arbitrary constants and \( \Delta \) and \( \xi \) are given by Equation (101).

When \( (a_{00} - V_3)^2 + 4C_\Delta < 0 \),

\[
\begin{align*}
\alpha_{12}(x, t) &= \alpha_{12}(\xi) = 2\sqrt{\Delta} \frac{C_2}{C_1 + C_2 \xi} + V_3, 
\end{align*}
\]

where \( \xi = x - V_3 t \), \( V_3, C_1, C_2, \) and \( a_{00} \) are arbitrary constants.

Moreover, note that Equation (76) is linear, so we can get the solution of Equation (65) as follows:

\[
\begin{align*}
\omega &= \sum_{i=1}^{n_1} \omega_{11} + \sum_{i=1}^{n_2} \omega_{12} + \sum_{i=1}^{n_3} \omega_{13} = 2\Delta(\ln \omega) + a_{00}, 
\end{align*}
\]
5. Bilinear Equation of the Boussinesq Equation and Sawada-Kotera Equation

In this section, we derive the bilinear equations of the Boussinesq equation and Sawada-Kotera equation by using the HB of undetermined coefficient method. Being similar to Section 4, we omit the process of solving exact solutions.

Example 1. The generalized Boussinesq equation reads

\[ u_{tt} + 2a u_{xt} + \left( \alpha^2 + \beta \right) u_{xx} + \gamma uu_{xx} + \delta u_{xxxx} = 0, \tag{111} \]

where \( \alpha, \beta, \gamma, \) and \( \delta \) are known constants.

In order to balance \( u_{xxxx} \) and \( uu_x \) in Equation (111), it is required that \( m + 4 = 2m + 2 \) and \( n = 2n \). Then, we suppose that the solution of Equation (111) is of the form

\[ u = a_{20}(\ln w)_{xx} + a_{10}(\ln w)_{x} + a_{00}, \tag{112} \]

where \( a_{i0} (i = 0, 1, 2) \) are constants to be determined later.

Substituting Equation (112) into Equation (111) and equating the coefficients of \((u_t/w)^6\) and \((u_t/w)^5\) on the left-hand side of Equation (111) to zero yield a set of algebraic equations for \( a_{20} \) and \( a_{10} \). Solving the algebraic equations, we get \( a_{20} = 6b/\gamma \) and \( a_{10} = 0 \). Substituting \( a_{20} \) and \( a_{10} \) back into Equation (112), we get

\[ u = \frac{6b}{\gamma} (\ln w)_{xx} + a_{00}, \tag{113} \]

where \( a_{00} \) is an arbitrary constant.

Substituting Equation (113) into Equation (111), we get

\[ \frac{6b}{\gamma} (K_1 + K_2 + K_3) = 0, \tag{114} \]

where

\[ K_1 = \beta \left( \frac{w_{xxxx}}{w} - \frac{3w_{xx}^2 + 4w_{x}w_{xxx}}{w^2} + \frac{12w_{xx}w_x^2}{w^3} - \frac{6w_x^4}{w^4} \right) + \alpha^2 \left( \frac{12w_{x}w_{xx}^2}{w^4} - \frac{3w_{xx}^2 + 4w_{xxx}w_x}{w^2} + \frac{w_{xxx}}{w} - \frac{6w_x^4}{w^4} \right) + \alpha \left( \frac{2w_{x}w_{xxx}}{w^3} - \frac{6w_{xxx}w_x + 6w_{x}w_{xx}}{w^2} + \frac{2w_{xxx}}{w} \right) + \frac{12w_{x}w_{x}w_{xx} + 12w_{x}w_{xx}w_x - 12w_{x}w_x^3}{w^3} + \frac{w_{xxx}}{w} - \frac{2w_{x}w_{x}w_{xx} + w_{xx}w_{x} + 2w_{x}w_{xxx} + 2w_{xxx}}{w^2} + \frac{2w_{x}w_{x}w_{x} + 2w_{x}w_{xx}^2 + 8w_{xx}w_{x}w_x - 6w_{x}w_x^3}{w^3} - \frac{6w_x^4}{w^4}, \]

\[ K_2 = a_{00} \left( \frac{2\gamma w_{xxxx}}{w} - \frac{8\gamma w_xw_{xxx} + 6\gamma w_x^3}{w^2} + \frac{24\gamma w_xw_{xx}^2}{w^3} - \frac{12\gamma w_x^4}{w^4} \right), \]

\[ K_3 = \delta \left( \frac{w_{xxxx}^2}{w} + \frac{2w_{xx}^2 - 6w_xw_{xxx} - 3w_x^2w_{xx}}{w^2} + \frac{18w_x^2w_{xxx} - 6w_x^3}{w^3} + \frac{18w_x^2w_{xx}^2 - 24w_x^4w_{xx}}{w^4} \right). \]

Simplifying Equation (114) and integrating twice with respect to \( x \), we get

\[ \frac{\partial^2}{\partial x^2} \left( (\alpha^2 + \beta + 2\gamma a_{00}) \left( \frac{ww_{xx} - w_x^2}{w^2} \right) + 2\alpha \left( \frac{ww_{xx} - w_x^2}{w^2} \right) \right) + \left( \frac{ww_{xx} - w_x^2}{w^2} \right) + \delta \left( \frac{ww_{xxx} - 4w_xw_{xxx}^3 + 3w_x^5}{w^2} \right) = 0. \tag{115} \]

Equation (116) is identical to

\[ (\alpha^2 + \beta + 2\gamma a_{00}) \left( \frac{ww_{xx} - w_x^2}{w^2} \right) + 2\alpha \left( \frac{ww_{xx} - w_x^2}{w^2} \right) + \left( \frac{ww_{xx} - w_x^2}{w^2} \right) + \delta \left( \frac{ww_{xxx} - 4w_xw_{xxx}^3 + 3w_x^5}{w^2} \right) = 0. \tag{117} \]

Equation (116) can be written concisely in terms of \( D \)-operators as

\[ (2aD_xD_t + \delta D_x^4 + (\alpha^2 + \beta + 2\gamma a_{00})D_x^2 + D_x^2)w \cdot w = 0, \tag{119} \]

where \( a_{00} \) is an arbitrary constant.

Example 2. The Sawada-Kotera equation reads

\[ u_t + 15(u^3 + uu_x)_x + u_{xxxx} = 0. \tag{120} \]

In order to balance \( u_{xxxx} \) and \( u^4 \) in Equation (120), it is required that \( m + 5 = 3m + 1 \) and \( n = 3n \). Then, we suppose that the solution of Equation (120) is of the form

\[ u = a_{20}(\ln w)_{xx} + a_{10}(\ln w)_{x} + a_{00}, \tag{121} \]

where \( a_{i0} (i = 0,1,2) \) are constants to be determined later.

Substituting Equation (121) into Equation (120) and equating the coefficients of \((u_t/w)^7\) and \((u_t/w)^6\) on the left-hand side of Equation (120) to zero yield a set of algebraic equations for \( a_{20} \) and \( a_{10} \). Solving the algebraic
where, we get $a_{20} = 2$ and $a_{10} = 0$. Substituting $a_{20}$ and $a_{10}$ back into Equation (121), we get

$$u = 2(\ln w)_{xx} + a_{00},$$

(122)

where $a_{00}$ is an arbitrary constant.

Substituting Equation (122) into Equation (120), we get

$$2(K_1 + K_2 + K_3) = 0,$$

(123)

where

$$K_1 = 45a_{00}^2 \left( \frac{w_{xxx}^2}{w} - 3w_x, w_{xx} - \frac{2w_x^3}{w^2} \right),$$

$$K_2 = 15a_{00} \left( \frac{w_{xxxx}^2}{w} + \frac{2w_x, w_{xxx} - 5w_x, w_{xxx}}{w^2} + \frac{8w_x, w_{xxx}, w_{xxx} - 6w_x, w_{xx}^2}{w^3} \right),$$

$$K_3 = \left( \frac{w_{xxx}}{w} - \frac{2w_x, w_{xx} + w_x, w_{xx}}{w^2} + \frac{2w_x^2 w_x}{w^3} \right)$$

$$+ \frac{9w_x, w_{xxx}, w_{xxx} - 5w_x, w_{xxx} - 7w_x, w_{xxxx}}{w^2}$$

$$+ \frac{20w_x, w_{xxx} - 30w_x, w_x, w_{xxx} + 12w_x^2 w_{xxxx}}{w^3}.$$  

(124)

Simplifying Equation (123) and integrating once with respect to $x$, we get

$$\frac{\partial}{\partial x} \left( 45a_{00}^2 \left( \frac{w_{xxx}^2}{w} - \frac{w_x^2}{w^2} \right) + 15a_{00} \left( \frac{w_{xxx}^2}{w} - \frac{4w_x, w_{xxx} + 3w_x^2}{w^2} \right) + \frac{ww_{xx} - w_x w_x}{w^2} + \frac{ww_{xxxx} - 6w_x, w_{xxx} + 15w_x, w_{xxx} - 10w_x^2}{w^2} \right) = 0.$$  

(125)

Equation (125) is identical to

$$45a_{00}^2 (w_{xxx}^2 - w_x^2) + 15a_{00} (w_{xxx}^2 - 4w_x, w_{xxx} + 3w_x^2) + (ww_{xx} - w_x w_x) + (ww_{xxxx} - 6w_x, w_{xxx} + 15w_x, w_{xxx} - 10w_x^2) - C(t) w^2 = 0,$$

(126)

where $C(t)$ is an arbitrary function of $t$ and $a_{00}$ is an arbitrary constant.

In particular, letting $C(t) = 0$ in Equation (126), we get the bilinear equation of Equation (120) as follows:

$$45a_{00}^2 (w_{xxx}^2 - w_x^2) + 15a_{00} (w_{xxx}^2 - 4w_x, w_{xxx} + 3w_x^2) + (ww_{xx} - w_x w_x) + (ww_{xxxx} - 6w_x, w_{xxx} + 15w_x, w_{xxx} - 10w_x^2) = 0.$$  

(127)

Equation (127) can be written concisely in terms of $D$-operators as

$$(45a_{00}^2 D_x^2 + 15a_{00} D_x^4 + D_x D_t + D_t) w \cdot w = 0,$$

(128)

where $a_{00}$ is an arbitrary constant.

### 6. Conclusions

The HB of undetermined coefficient method is successfully used to establish the bilinear equation of NLPE. By applying the perturbation method, sub-ODE method, and compatible condition to the bilinear equation, more exact solutions of NLPE are obtained. We illustrate the real meaning of balance numbers. We show the underlying relations among the $(G'/G)^{expansion}$-expansion method, Hirota's method, and HB method. Many well-known NLPE can be handled by the HB of undetermined coefficient method. The performance of our method is found to be simple and efficient. The availability of computer systems like Maple facilitates the tedious algebraic calculations. Our method is also a standard and computable method, which allows us to solve complicated and tedious algebraic calculations.

### Data Availability

The data used to support the findings of this study are available from the corresponding author upon request.

### Conflicts of Interest

The authors declare no competing interests.

### Authors’ Contributions

Xiao-Feng Yang analyzed and interpreted the data and wrote the manuscript; Yi Wei designed and optimized the algorithm and program. All authors read the manuscript.

### Acknowledgments

The research is supported by the Fundamental Research Funds for the Central Universities (2452017373), the Doctoral Research Foundation of Northwest A&F University (2452017007), the Project of Shandong Province Higher Educational Science and Technology Program (J18KB100), the NSFC Cultivation Project of Jining Medical University (JYP2018KJ15), the Doctoral Research Foundation of Jining Medical University (2017YQD22).
References


