

Math 211

Lecture #38

Linearization in Higher Dimension

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Linearization of a Planar System

$$x' = f(x, y)$$

$$y' = g(x, y)$$

- (x_0, y_0) is an equilibrium point so

$$f(x_0, y_0) = g(x_0, y_0) = 0$$

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Linearization at (x_0, y_0)

$$\tilde{u}' = \frac{\partial f}{\partial x}(x_0, y_0)\tilde{u} + \frac{\partial f}{\partial y}(x_0, y_0)\tilde{v}$$

$$\tilde{v}' = \frac{\partial g}{\partial x}(x_0, y_0)\tilde{u} + \frac{\partial g}{\partial y}(x_0, y_0)\tilde{v}$$

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Original system

Matrix Form of the Linearization

Set $\mathbf{u} = (\tilde{u}, \tilde{v})^T$ and introduce the *Jacobian matrix*

$$J = \begin{pmatrix} \frac{\partial f}{\partial x}(x_0, y_0) & \frac{\partial f}{\partial y}(x_0, y_0) \\ \frac{\partial g}{\partial x}(x_0, y_0) & \frac{\partial g}{\partial y}(x_0, y_0) \end{pmatrix}$$

- The linearization becomes

$$\mathbf{u}' = J\mathbf{u}.$$

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[Linear system](#)

[Original system](#)

Theorem: Consider the planar system

$$x' = f(x, y)$$

$$y' = g(x, y)$$

where f and g are continuously differentiable.

Suppose that (x_0, y_0) is an equilibrium point. If the linearization at (x_0, y_0) has a generic equilibrium point at the origin, then the equilibrium point at (x_0, y_0) is of the same type.

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[Matrix form](#)

[Generic](#)

Generic Equilibrium Points

- Saddle, nodal source, nodal sink, spiral source, and spiral sink.
 - ◊ All occupy large open subsets of the trace-determinant plane.
- Nongeneric types
 - ◊ Center and eight others. Occupy pieces of the boundaries.

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[Theorem](#)

Higher Dimensional Systems

Autonomous equation $\mathbf{y}' = \mathbf{f}(\mathbf{y})$

- $\mathbf{y} = (y_1, y_2, \dots, y_n)^T$
- $\mathbf{f}(\mathbf{y}) = (f_1(\mathbf{y}), f_2(\mathbf{y}), \dots, f_n(\mathbf{y}))^T$
- J is the Jacobian matrix

$$\mathbf{f}(\mathbf{y}_0 + \mathbf{u}) = J(\mathbf{y}_0)\mathbf{u} + \mathbf{R}(\mathbf{u})$$

$$\text{where } \lim_{\mathbf{u} \rightarrow \mathbf{0}} \frac{\mathbf{R}(\mathbf{u})}{|\mathbf{u}|} = \mathbf{0}.$$

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Set $\mathbf{y} = \mathbf{y}_0 + \mathbf{u}$. The system becomes

$$\mathbf{u}' = J(\mathbf{y}_0)\mathbf{u} + \mathbf{R}(\mathbf{u}).$$

The linearization is

$$\mathbf{u}' = J(\mathbf{y}_0)\mathbf{u}.$$

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HDSYS

Theorem: Suppose that \mathbf{y}_0 is an equilibrium point for $\mathbf{y}' = \mathbf{f}(\mathbf{y})$. Let J be the Jacobian of \mathbf{f} at \mathbf{y}_0 .

1. Suppose that the real part of every eigenvalue of J is negative. Then \mathbf{y}_0 is an asymptotically stable equilibrium point.
2. Suppose that J has at least one eigenvalue with positive real part. Then \mathbf{y}_0 is an unstable equilibrium point.

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Theorem 1

Example

$$x' = -2x - 4y + 2xy$$

$$y' = x - 6y + x^2 - y^2$$

- One eigenvalue $\lambda = -4$ of algebraic multiplicity 2.
- First theorem does not apply.
- Second theorem does apply. The origin is a sink.

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The Lorenz System

$$x' = -ax + ay$$

$$y' = rx - y - xz$$

$$z' = -bz + xy$$

Equilibrium points.

- ($r \leq 1$) $(0, 0, 0)$
- ($r > 1$) Set $s = \sqrt{b(r-1)}$.
 $(0, 0, 0)$, $\mathbf{c}^+ = (s, s, r-1)$ & $\mathbf{c}^- = (-s, -s, r-1)$

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- The Jacobian is

$$J = \begin{pmatrix} -a & a & 0 \\ r - z & -1 & -x \\ y & x & -b \end{pmatrix}$$

- ◊ Use $a = 10$ and $b = 8/3$.
- ◊ $(0, 0, 0)$
 - ★ If $r < 1$ $(0, 0, 0)$ is asymptotically stable.
 - ★ If $r > 1$ $(0, 0, 0)$ is unstable.

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- ◇ c^+ and c^-
 - ★ For $1 < r < 470/19 \approx 24.74$, c^+ and c^- are asymptotically stable.
 - ★ For $r > 470/19 \approx 24.74$, c^+ and c^- are unstable.

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Jacobian

 c^+ & c^-

- ◇ As r varies the Lorenz system displays a wide variety of behaviors.
 - ★ For $r = 28$ we have Lorenz's strange attractor.
 - ★ For $r = 100$ there is a periodic attractor.
 - ★ For $r = 200$ there is another strange attractor.

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Invariant Sets

Definition: A set S is (positively) invariant for the system $\mathbf{y}' = \mathbf{f}(\mathbf{y})$ if $\mathbf{y}(0) = \mathbf{y}_0 \in S$ implies that $\mathbf{y}(t) \in S$ for all $t \geq 0$.

- Examples:
 - ◇ An equilibrium point.
 - ◇ Any solution curve.

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Example — Competing Species

$$x' = (5 - 2x - y)x$$

$$y' = (7 - 2x - 3y)y$$

- The positive x - and y -axes are invariant.
- The positive quadrant is invariant.
 - ◊ Populations should remain nonnegative.
- The set $S = \{(x, y) \mid 0 < x < 3, 0 < y < 3\}$ is positively invariant.

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Nullclines

$$x' = f(x, y)$$

$$y' = g(x, y)$$

Definition: The x -nullcline is the set defined by $f(x, y) = 0$. The y -nullcline is the set defined by $g(x, y) = 0$.

- Along the x -nullcline the vector field points up or down.
- Along the y -nullcline the vector field points left or right.

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Competing Species

$$x' = (5 - 2x - y)x$$

$$y' = (7 - 2x - 3y)y$$

- The x -nullcline consists of the two lines $x = 0$ and $2x + y = 5$.
- The y -nullcline consists of the two lines $y = 0$ and $2x + 3y = 7$.
- The nullclines intersect at the equilibrium points.

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[Nullclines](#)

- Two of the in the positive quadrant defined by the nullclines are positively invariant.
- This information allows us to predict that all solutions in the positive quadrant $\rightarrow (2, 1)$ as $t \rightarrow \infty$.

four regions

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Competing Species – 2nd Example

$$x' = (1 - x - y)x$$

$$y' = (4 - 7x - 3y)y$$

- The equilibrium point at $(1/4, 3/4)$ is a saddle point.
- All solutions go to either $(0, 4/3)$ or $(1, 0)$.

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Definition: The *basin of attraction* of a sink \mathbf{y}_0 consists of all points \mathbf{y} such that the solution starting at \mathbf{y} approaches \mathbf{y}_0 as $t \rightarrow \infty$.

- In the example, the basins of attraction of the two sinks are separated by the stable orbits of the saddle point.
- The stable and unstable orbits of a saddle point are called *separatrices*. (Separatrices is the plural of separatrix.)

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