

Null Controllability of Coupled Parabolic Degenerate Equations

L. Maniar, University Cadi ayyad, Marrakesh

M. Ait Ben hassi, Marrakesh,
F. Ammar Khodja, Besançon,
A. Hajjaj, Marrakesh

Partial Differential Equations, Benasque
Aug 28 – Sep 09, 2011

Coupled Parabolic Systems

$$u_t - (a_1(x)u_x)_x + c_1(t, x)u + b_1(t, x)v = h_1 1_\omega,$$

$$v_t - (a_2(x)v_x)_x + c_2(t, x)v + b_2(t, x)u = 0,$$

+ Boundary Conditions

$$u(0, x) = u_0(x), \quad v(0, x) = v_0(x), \quad x \in (0, 1),$$

$$\exists? h_1 : \quad u(T) = v(T) = 0.$$

Nondegenerate Case : $a_i(x) \geq m > 0$

Gonzalez-Burgos, De Teresa, Ammar-Khodja,
Benabdellah, Dupaix, Zuazua, ...

Coupled Parabolic Systems

$$u_t - (a_1(x)u_x)_x + c_1(t, x)u + b_1(t, x)v = h_1 1_\omega,$$

$$v_t - (a_2(x)v_x)_x + c_2(t, x)v + b_2(t, x)u = 0,$$

+ Boundary Conditions

$$u(0, x) = u_0(x), \quad v(0, x) = v_0(x), \quad x \in (0, 1),$$



$$\exists? h_1 : \quad u(T) = v(T) = 0.$$



Nondegenerate Case : $a_i(x) \geq m > 0$



Gonzalez-Burgos, De Teresa, Ammar-Khodja,
Benabdellah, Dupaix, Zuazua, ...

Coupled Parabolic Systems

$$u_t - (a_1(x)u_x)_x + c_1(t, x)u + b_1(t, x)v = h_1 \mathbf{1}_\omega,$$

$$v_t - (a_2(x)v_x)_x + c_2(t, x)v + b_2(t, x)u = 0,$$

+ Boundary Conditions

$$u(0, x) = u_0(x), \quad v(0, x) = v_0(x), \quad x \in (0, 1),$$



$$\exists? h_1 : \quad u(T) = v(T) = 0.$$



Nondegenerate Case : $a_i(x) \geq m > 0$



Gonzalez-Burgos, De Teresa, Ammar-Khodja,
Benabdellah, Dupaix, Zuazua, ...

Coupled Parabolic Systems

$$u_t - (a_1(x)u_x)_x + c_1(t, x)u + b_1(t, x)v = h_1 \mathbf{1}_\omega,$$

$$v_t - (a_2(x)v_x)_x + c_2(t, x)v + b_2(t, x)u = 0,$$

+ Boundary Conditions

$$u(0, x) = u_0(x), \quad v(0, x) = v_0(x), \quad x \in (0, 1),$$



$$\exists? h_1 : \quad u(T) = v(T) = 0.$$



Nondegenerate Case : $a_i(x) \geq m > 0$



Gonzalez-Burgos, De Teresa, Ammar-Khodja,
Benabdellah, Dupaix, Zuazua, ...

Degenerate Coupled Parabolic Systems

- $a_i(0) = 0$ e.g. $a_i(x) = x^{\alpha_i}$
- $a_i(0) = a_i(1) = 0$ e.g. $a_i(x) = x^{\alpha_i}(1-x)^{\beta_i}$

Degenerate Coupled Parabolic Systems

- $a_i(0) = 0$ e.g. $a_i(x) = x^{\alpha_i}$
- $a_i(0) = a_i(1) = 0$ e.g. $a_i(x) = x^{\alpha_i}(1-x)^{\beta_i}$

Degenerate Parabolic Cascade Systems

Cannarsa and De Teresa : $a_1 = a_2 =: a$, $b_1 = 0$

$$u_t - (a(x)u_x)_x + c_1(t, x)u = h_1 1_\omega,$$

$$v_t - (a(x)v_x)_x + c_2(t, x)v + b_2(t, x)u = 0,$$

$$u(t, 1) = v(t, 1) = 0$$

$$u(t, 0) = v(t, 0) = 0 \quad (\text{Weak deg.})$$

or

$$(au_x)(0) = (av_x)(0) = 0 \quad (\text{Strong deg.})$$

$$u(0, x) = u_0(x), \quad v(0, x) = v_0(x), \quad x \in (0, 1),$$

Degenerate Parabolic Cascade Systems



$$a(x) = x^\alpha$$



(Weak deg.) $\iff 0 \leq \alpha < 1$.



(Strong deg.) $\iff 1 \leq \alpha < 2$.

Degenerate Parabolic Cascade Systems



$$a(x) = x^\alpha$$



(Weak deg.) $\iff 0 \leq \alpha < 1$.



(Strong deg.) $\iff 1 \leq \alpha < 2$.

Degenerate Parabolic Cascade Systems



$$a(x) = x^\alpha$$

- (Weak deg.) $\iff 0 \leq \alpha < 1.$

- (Strong deg.) $\iff 1 \leq \alpha < 2.$

Adjoint Degenerate Cascade Systems

$$U_t - (a_1(x)U_x)_x + c_1(t, x)U + b_2(t, x)V = 0,$$

$$V_t - (a_2(x)V_x)_x + c_2(t, x)V = 0,$$

$$u(t, 1) = v(t, 1) = 0$$

$$u(t, 0) = 0 \text{ (Weak deg.) or } (au_x)(0) = 0 \text{ (Strong deg.)}$$

$$v(t, 0) = 0 \text{ (Weak deg.) or } (av_x)(0) = 0 \text{ (Strong deg.)}$$

$$U(0, x) = U_0(x), \quad V(0, x) = V_0(x), \quad x \in (0, 1),$$

$$a_1 = x^{\alpha_1}, \quad a_2 = x^{\alpha_2}.$$

Adjoint Degenerate Cascade Systems

$$U_t - (a_1(x)U_x)_x + c_1(t, x)U + b_2(t, x)V = 0,$$

$$V_t - (a_2(x)V_x)_x + c_2(t, x)V = 0,$$

$$u(t, 1) = v(t, 1) = 0$$

$$u(t, 0) = 0 \text{ (Weak deg.) or } (au_x)(0) = 0 \text{ (Strong deg.)}$$

$$v(t, 0) = 0 \text{ (Weak deg.) or } (av_x)(0) = 0 \text{ (Strong deg.)}$$

$$U(0, x) = U_0(x), \quad V(0, x) = V_0(x), \quad x \in (0, 1),$$

$$a_1 = x^{\alpha_1}, \quad a_2 = x^{\alpha_2}.$$

Carleman Estimate

Theorem 1

$\exists C > 0, \exists s_0 > 0 \quad / \quad \forall (U, V), \forall s \geq s_0 :$

$$\begin{aligned} & \int_0^T \int_0^1 \left[s \Theta a_1 U_x^2 + s^3 \Theta^3 \frac{x^2}{a_1(x)} U^2 \right] e^{2s\varphi_1} dx dt \\ & + \int_0^T \int_0^1 \left[s \Theta a_2 V_x^2 + s^3 \Theta^3 \frac{x^2}{a_2(x)} V^2 \right] e^{2s\varphi_2} dx dt \\ & \leq C \int_0^T \int_\omega [U^2 + V^2] e^{2s\Phi_2} dx dt. \end{aligned}$$

Weight functions

$$\Theta(t) := \frac{1}{[t(T-t)]^4},$$

$$\psi_i(x) := \lambda_i \left(\int_0^x \frac{y}{a_i(y)} dy - d_i \right) = \lambda_i (x^{2-\alpha_i} - d_i)$$

$$\varphi_i(t, x) = \Theta(t)\psi_i(x), \quad i = 1, 2,$$

$$\Psi_i(x) := e^{r_i \zeta_i(x)} - e^{2\rho_i},$$

$$\zeta_i(x) := \int_x^1 \frac{1}{\sqrt{a_i(y)}} dy, \quad \rho_i := r_i \zeta_i(0),$$

$$\Phi_i(t, x) := \Theta(t)\Psi_i(x) \quad i = 1, 2.$$

Weight functions

$$\Theta(t) := \frac{1}{[t(T-t)]^4},$$

$$\psi_i(x) := \lambda_i \left(\int_0^x \frac{y}{a_i(y)} dy - d_i \right) = \lambda_i (x^{2-\alpha_i} - d_i)$$

$$\varphi_i(t, x) = \Theta(t)\psi_i(x), \quad i = 1, 2,$$

$$\Psi_i(x) := e^{r_i\zeta_i(x)} - e^{2\rho_i},$$

$$\zeta_i(x) := \int_x^1 \frac{1}{\sqrt{a_i(y)}} dy, \quad \rho_i := r_i\zeta_i(0),$$

$$\Phi_i(t, x) := \Theta(t)\Psi_i(x) \quad i = 1, 2.$$

Proof

$$\omega = (a, b) \subset\subset (0, 1).$$

Estimate in $(0, a)$

ξ = cut-off function ;

$$w := \xi U, \quad z := \xi V,$$

$$w_t - (a_1 w_x)_x + c_1 w = b_2 z - \xi_x a_1 U_x - (a_1 \xi_x U)_x =: f_1,$$

$$z_t - (a_2 z_x)_x + c_2 z = -\xi_x a_2 V_x - (a_2 \xi_x V)_x =: f_2,$$

+ Boundary conditions

$$w(0, x) = w_0(x), z(0, x) = z_0(x).$$

Proof

$$\omega = (a, b) \subset\subset (0, 1).$$

Estimate in $(0, a)$

ξ = cut-off function ;

$$w := \xi U, \quad z := \xi V,$$

$$w_t - (a_1 w_x)_x + c_1 w = b_2 z - \xi_x a_1 U_x - (a_1 \xi_x U)_x =: f_1,$$

$$z_t - (a_2 z_x)_x + c_2 z = -\xi_x a_2 V_x - (a_2 \xi_x V)_x =: f_2,$$

+ Boundary conditions

$$w(0, x) = w_0(x), z(0, x) = z_0(x).$$

Proof

$$\omega = (a, b) \subset\subset (0, 1).$$

Estimate in $(0, a)$

ξ = cut-off function ;

$$w := \xi U, \quad z := \xi V,$$

$$w_t - (a_1 w_x)_x + c_1 w = b_2 z - \xi_x a_1 U_x - (a_1 \xi_x U)_x =: f_1,$$

$$z_t - (a_2 z_x)_x + c_2 z = -\xi_x a_2 V_x - (a_2 \xi_x V)_x =: f_2,$$

+ Boundary conditions

$$w(0, x) = w_0(x), z(0, x) = z_0(x).$$

Proof

$$\omega = (a, b) \subset\subset (0, 1).$$

Estimate in $(0, a)$

ξ = cut-off function ;

$$w := \xi U, \quad z := \xi V,$$

$$w_t - (a_1 w_x)_x + c_1 w = b_2 z - \xi_x a_1 U_x - (a_1 \xi_x U)_x =: f_1,$$

$$z_t - (a_2 z_x)_x + c_2 z = -\xi_x a_2 V_x - (a_2 \xi_x V)_x =: f_2,$$

+ Boundary conditions

$$w(0, x) = w_0(x), z(0, x) = z_0(x).$$

Proof

$$\begin{aligned} & \int_0^T \int_0^1 [s\Theta a_1 w_x^2 + s^3\Theta^3 \frac{x^2}{a_1(x)} w^2] e^{2s\varphi_1} dx dt \\ & \leq C \int_0^T \int_0^1 [b_2^2 z^2 + (\xi_x a_1 U_x + (a_1 \xi_x U)_x)^2] e^{2s\varphi_1} dx dt \end{aligned}$$

$$\begin{aligned} & \int_0^T \int_0^1 [s\Theta a_2 z_x^2 + s^3\Theta^3 \frac{x^2}{a_2(x)} z^2] e^{2s\varphi_2} dx dt \\ & \leq C \int_0^T \int_0^1 (\xi_x a_2 V_x + (a_2 \xi_x V)_x)^2 e^{2s\varphi_2} dx dt. \end{aligned}$$

Proof

$$\begin{aligned} & \int_0^T \int_0^1 \left[s\Theta a_1 w_x^2 + s^3\Theta^3 \frac{x^2}{a_1(x)} w^2 \right] e^{2s\varphi_1} dx dt \\ & \leq C \int_0^T \int_0^1 \left[b_2^2 z^2 + (\xi_x a_1 U_x + (a_1 \xi_x U)_x)^2 \right] e^{2s\varphi_1} dx dt \end{aligned}$$

$$\begin{aligned} & \int_0^T \int_0^1 \left[s\Theta a_2 z_x^2 + s^3\Theta^3 \frac{x^2}{a_2(x)} z^2 \right] e^{2s\varphi_2} dx dt \\ & \leq C \int_0^T \int_0^1 (\xi_x a_2 V_x + (a_2 \xi_x V)_x)^2 e^{2s\varphi_2} dx dt. \end{aligned}$$

- $d_i \geq \max\left\{\frac{1}{a_i(1)(2-K)}, 4 \int_0^1 \frac{y}{a_i(y)} dy\right\},$
- $e^{\rho_2} \geq 4 \frac{d_2 - \int_0^1 \frac{y}{a_2(y)} dy}{d_2 - 4 \int_0^1 \frac{y}{a_2(y)} dy},$
- $\rho_1 = 2\rho_2,$
- $\lambda_1 = \frac{e^{2\rho_1} - 1}{d_1 - \int_0^1 \frac{y}{a_1(y)} dy}, \quad \lambda_2 = \frac{4}{3d_2} (e^{2\rho_2} - e^{\rho_2}).$

Weight functions comparison

For this choice we have :

- $\varphi_1 \leq \varphi_2,$
- $\Phi_1 \leq \Phi_2,$
- $\varphi_i \leq \Phi_i.$

Hardy-Poincaré Inequality

$$\int_0^1 \frac{a_i(x)}{x^2} g^2(x) dx \leq C \int_0^1 a_i(x) |g_x|^2 dx$$

$$\int_0^1 x^{\gamma-2} g^2(x) dx \leq C \int_0^1 x^\gamma |g_x|^2 dx$$

$$0 \leq \gamma < 2, \gamma \neq 1$$

Hardy-Poincaré Inequality

$$\int_0^1 \frac{a_i(x)}{x^2} g^2(x) dx \leq C \int_0^1 a_i(x) |g_x|^2 dx$$

$$\int_0^1 x^{\gamma-2} g^2(x) dx \leq C \int_0^1 x^\gamma |g_x|^2 dx$$

$$0 \leq \gamma < 2, \gamma \neq 1$$

Non Cascade degenerate Systems

$$U_t - (x^{\alpha_1} U_x)_x + c_1(t, x)U + b_2(t, x)V = 0,$$

$$V_t - (x^{\alpha_2} V_x)_x + c_2(t, x)V + b_1(t, x)U = 0,$$

+ Boundary Conditions

$$U(0, x) = U_0(x), \quad V(0, x) = V_0(x)$$

$$\begin{aligned}
& \int_0^T \int_0^1 [s\Theta a_1 w_x^2 + s^3 \Theta^3 \frac{x^2}{a_1(x)} w^2] e^{2s\varphi_1} dx dt \\
& \leq C \int_0^T \int_0^1 [b_2^2 z^2 + (\xi_x a_1 U_x + (a_1 \xi_x U)_x)^2] e^{2s\varphi_1} dx dt
\end{aligned}$$

$$\begin{aligned}
& \int_0^T \int_0^1 [s\Theta a_2 z_x^2 + s^3 \Theta^3 \frac{x^2}{a_2(x)} z^2] e^{2s\varphi_2} dx dt \\
& \leq C \int_0^T \int_0^1 (b_1^2 w^2 + \xi_x a_2 V_x + (a_2 \xi_x V)_x)^2] e^{2s\varphi_2} dx dt.
\end{aligned}$$

New Carleman estimate of parabolic equations

$$y_t - (x^\alpha y_x)_x = f,$$

+ boundary conditions

$$y(0, x) = y_0, x \in (0, 1).$$

Previous

$$\psi(x) = c_1(x^{2-\alpha} - c_2).$$

New

$$\psi(x) = c_1(x^{2-\beta} - c_2).$$

New Carleman estimate of parabolic equations

$$y_t - (x^\alpha y_x)_x = f,$$

+ boundary conditions

$$y(0, x) = y_0, x \in (0, 1).$$

Previous

$$\psi(x) = c_1(x^{2-\alpha} - c_2).$$

New

$$\psi(x) = c_1(x^{2-\beta} - c_2).$$

New Carleman estimate of parabolic equations

$$y_t - (x^\alpha y_x)_x = f,$$

+ boundary conditions

$$y(0, x) = y_0, x \in (0, 1).$$

Previous

$$\psi(x) = c_1(x^{2-\alpha} - c_2).$$

New

$$\psi(x) = c_1(x^{2-\beta} - c_2).$$

New Carleman estimate of parabolic equations

Let $0 \leq \alpha < 1$.

$\forall \beta \in [\alpha, 1), \exists C, s_0 > 0 :$

$$\begin{aligned} & \int_0^T \int_0^1 (s\Theta(t)x^{2\alpha-\beta}y_x^2 + s^3\Theta^3(t)x^{2+2\alpha-3\beta}y^2)e^{2s\varphi} dxdt \\ & \leq C \int_0^T \int_0^1 f^2(t,x)e^{2s\varphi(t,x)} dxdt \\ & + \int_0^T s\Theta(t)y_x^2(t,1)e^{2s\varphi(t,1)} dt, \quad \forall s \geq s_0 \end{aligned}$$

$$\beta \in [\max(\alpha_1, \alpha_2), 1).$$

New Carleman estimate of parabolic equations

Let $0 \leq \alpha < 1$.

$\forall \beta \in [\alpha, 1), \exists C, s_0 > 0 :$

$$\begin{aligned} & \int_0^T \int_0^1 (s\Theta(t)x^{2\alpha-\beta}y_x^2 + s^3\Theta^3(t)x^{2+2\alpha-3\beta}y^2)e^{2s\varphi} dxdt \\ & \leq C \int_0^T \int_0^1 f^2(t,x)e^{2s\varphi(t,x)} dxdt \\ & + \int_0^T s\Theta(t)y_x^2(t,1)e^{2s\varphi(t,1)} dt, \quad \forall s \geq s_0 \end{aligned}$$

$$\beta \in [\max(\alpha_1, \alpha_2), 1).$$

Difficulties and Open Problems

Null controllability for systems

- Weak-Strong : e.g. $\alpha_1 < 1$ and $\alpha_2 \geq 1$.
- Strong-Strong : $\alpha_1 \geq 1$ and $\alpha_2 \geq 1$.
- General $a_i, i = 1, 2$.
- High dimension

Null controllability for systems

- Weak-Strong : e.g. $\alpha_1 < 1$ and $\alpha_2 \geq 1$.
- Strong-Strong : $\alpha_1 \geq 1$ and $\alpha_2 \geq 1$.
- General $a_i, i = 1, 2$.
- High dimension

Null controllability for systems

- Weak-Strong : e.g. $\alpha_1 < 1$ and $\alpha_2 \geq 1$.
- Strong-Strong : $\alpha_1 \geq 1$ and $\alpha_2 \geq 1$.
- General $a_i, i = 1, 2$.
- High dimension

Null controllability for systems

- Weak-Strong : e.g. $\alpha_1 < 1$ and $\alpha_2 \geq 1$.
- Strong-Strong : $\alpha_1 \geq 1$ and $\alpha_2 \geq 1$.
- General $a_i, i = 1, 2$.
- High dimension

Null controllability for systems

- Weak-Strong : e.g. $\alpha_1 < 1$ and $\alpha_2 \geq 1$.
- Strong-Strong : $\alpha_1 \geq 1$ and $\alpha_2 \geq 1$.
- General $a_i, i = 1, 2$.
- High dimension

$$u_t - (x^{\alpha_1} u_x)_x + c_1(t, x)u + b_1(t, x)v = 0$$

$$v_t - (x^{\alpha_2} v_x)_x + c_2(t, x)v + b_2(t, x)u = 0,$$

$$u(t, 1) = v(t, 1) = 0$$

$$u(t, 0) = g_1(t), \quad v(t, 0) = g_2(t)$$

$$u(0, x) = u_0(x), \quad v(0, x) = v_0(x).$$

Inverse problem for parabolic systems

$$u_t - (x^{\alpha_1} u_x)_x + c_1(t, x)u + b_1(t, x)v = f,$$

$$v_t - (x^{\alpha_2} v_x)_x + c_2(t, x)v + b_2(t, x)u = g,$$

+ Boundary Conditions

$$u(0, x) = u_0(x), \quad v(0, x) = v_0(x).$$

Choukran=Gracias=Thank you