

# Rate independent hysteresis as a limit case of slow-fast systems

Pavel Krejčí

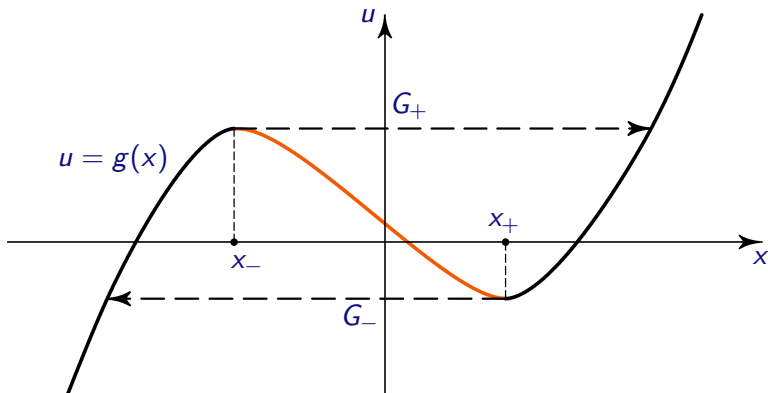
Matematický ústav AV ČR, Praha

International Workshop on Hysteresis and Slow-Fast Systems

Wittenberg, December 12, 2011

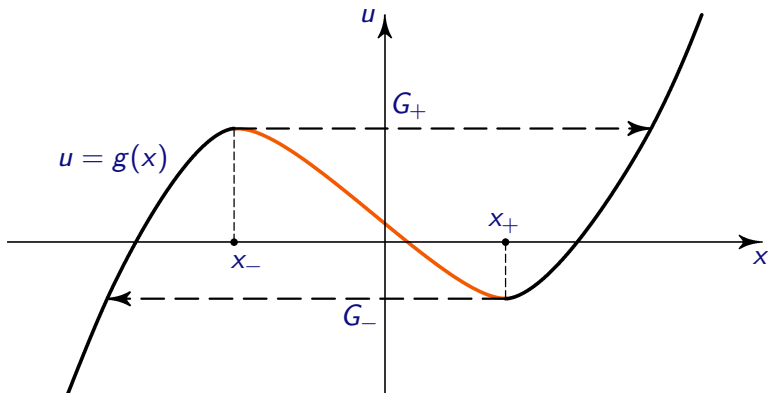
## Limit behavior in a singularly perturbed problem

$$\alpha \dot{x}(t) + g(x(t)) = u(t), \quad x(0) = x_0$$



## Limit behavior in a singularly perturbed problem

$$\alpha \dot{x}(t) + g(x(t)) = u(t), \quad x(0) = x_0$$



Which is the right convergence concept as  $\alpha \rightarrow 0+$ ?

## Physical motivation: unstable spontaneous pressure oscillations in a pump-valve system

## Physical motivation: unstable spontaneous pressure oscillations in a pump-valve system

Consider a fluid flow in a tube of length  $\ell$  along the  $x$ -axis with a pump at  $x = 0$  and valve at  $x = \ell$ , assuming linear volume-pressure law

$$\begin{aligned} \varrho v_t + p_x &= 0 \\ p_t + K v_x &= 0 \end{aligned} \quad \text{for } (x, t) \in ]0, \ell[ \times ]0, \infty[ ,$$

where  $p$  and  $v$  are the pressure and velocity, respectively,  $\varrho$  is the mass density, and  $K > 0$  is a material constant,

## Physical motivation: unstable spontaneous pressure oscillations in a pump-valve system

Consider a fluid flow in a tube of length  $\ell$  along the  $x$ -axis with a pump at  $x = 0$  and valve at  $x = \ell$ , assuming linear volume-pressure law

$$\begin{aligned} \varrho v_t + p_x &= 0 \\ p_t + K v_x &= 0 \end{aligned} \quad \text{for } (x, t) \in ]0, \ell[ \times ]0, \infty[ ,$$

where  $p$  and  $v$  are the pressure and velocity, respectively,  $\varrho$  is the mass density, and  $K > 0$  is a material constant, with boundary conditions

$$\begin{aligned} \alpha v_t(0, t) + f(v(0, t)) + p(0, t) &= p_e + \bar{p}(t) \\ p(\ell, t) &= M v(\ell, t) \end{aligned}$$

## Physical motivation: unstable spontaneous pressure oscillations in a pump-valve system

Consider a fluid flow in a tube of length  $\ell$  along the  $x$ -axis with a pump at  $x = 0$  and valve at  $x = \ell$ , assuming linear volume-pressure law

$$\begin{aligned} \rho v_t + p_x &= 0 \\ p_t + K v_x &= 0 \end{aligned} \quad \text{for } (x, t) \in ]0, \ell[ \times ]0, \infty[ ,$$

where  $p$  and  $v$  are the pressure and velocity, respectively,  $\rho$  is the mass density, and  $K > 0$  is a material constant, with boundary conditions

$$\begin{aligned} \alpha v_t(0, t) + f(v(0, t)) + p(0, t) &= p_e + \bar{p}(t) \\ p(\ell, t) &= M v(\ell, t) \end{aligned}$$

where  $\alpha > 0$  is a (small) constant called “pump inertance”,

## Physical motivation: unstable spontaneous pressure oscillations in a pump-valve system

Consider a fluid flow in a tube of length  $\ell$  along the  $x$ -axis with a pump at  $x = 0$  and valve at  $x = \ell$ , assuming linear volume-pressure law

$$\begin{aligned} \varrho v_t + p_x &= 0 \\ p_t + K v_x &= 0 \end{aligned} \quad \text{for } (x, t) \in ]0, \ell[ \times ]0, \infty[ ,$$

where  $p$  and  $v$  are the pressure and velocity, respectively,  $\varrho$  is the mass density, and  $K > 0$  is a material constant, with boundary conditions

$$\begin{aligned} \alpha v_t(0, t) + f(v(0, t)) + p(0, t) &= p_e + \bar{p}(t) \\ p(\ell, t) &= M v(\ell, t) \end{aligned}$$

where  $\alpha > 0$  is a (small) constant called “pump inertance”,  $f$  is a continuous (non-monotone) function describing the velocity-pressure characteristic of the pump,



## Physical motivation: unstable spontaneous pressure oscillations in a pump-valve system

Consider a fluid flow in a tube of length  $\ell$  along the  $x$ -axis with a pump at  $x = 0$  and valve at  $x = \ell$ , assuming linear volume-pressure law

$$\begin{aligned} \varrho v_t + p_x &= 0 \\ p_t + K v_x &= 0 \end{aligned} \quad \text{for } (x, t) \in ]0, \ell[ \times ]0, \infty[ ,$$

where  $p$  and  $v$  are the pressure and velocity, respectively,  $\varrho$  is the mass density, and  $K > 0$  is a material constant, with boundary conditions

$$\begin{aligned} \alpha v_t(0, t) + f(v(0, t)) + p(0, t) &= p_e + \bar{p}(t) \\ p(\ell, t) &= M v(\ell, t) \end{aligned}$$

where  $\alpha > 0$  is a (small) constant called “pump inertance”,  $f$  is a continuous (non-monotone) function describing the velocity-pressure characteristic of the pump,  $M > 0$  is the valve parameter,

## Physical motivation: unstable spontaneous pressure oscillations in a pump-valve system

Consider a fluid flow in a tube of length  $\ell$  along the  $x$ -axis with a pump at  $x = 0$  and valve at  $x = \ell$ , assuming linear volume-pressure law

$$\begin{aligned} \varrho v_t + p_x &= 0 \\ p_t + K v_x &= 0 \end{aligned} \quad \text{for } (x, t) \in ]0, \ell[ \times ]0, \infty[ ,$$

where  $p$  and  $v$  are the pressure and velocity, respectively,  $\varrho$  is the mass density, and  $K > 0$  is a material constant, with boundary conditions

$$\begin{aligned} \alpha v_t(0, t) + f(v(0, t)) + p(0, t) &= p_e + \bar{p}(t) \\ p(\ell, t) &= M v(\ell, t) \end{aligned}$$

where  $\alpha > 0$  is a (small) constant called “pump inertance”,  $f$  is a continuous (non-monotone) function describing the velocity-pressure characteristic of the pump,  $M > 0$  is the valve parameter,  $p_e$  is a constant external pressure,

## Physical motivation: unstable spontaneous pressure oscillations in a pump-valve system

Consider a fluid flow in a tube of length  $\ell$  along the  $x$ -axis with a pump at  $x = 0$  and valve at  $x = \ell$ , assuming linear volume-pressure law

$$\begin{aligned} \rho v_t + p_x &= 0 \\ p_t + K v_x &= 0 \end{aligned} \quad \text{for } (x, t) \in ]0, \ell[ \times ]0, \infty[ ,$$

where  $p$  and  $v$  are the pressure and velocity, respectively,  $\rho$  is the mass density, and  $K > 0$  is a material constant, with boundary conditions

$$\begin{aligned} \alpha v_t(0, t) + f(v(0, t)) + p(0, t) &= p_e + \bar{p}(t) \\ p(\ell, t) &= M v(\ell, t) \end{aligned}$$

where  $\alpha > 0$  is a (small) constant called “pump inertance”,  $f$  is a continuous (non-monotone) function describing the velocity-pressure characteristic of the pump,  $M > 0$  is the valve parameter,  $p_e$  is a constant external pressure, and  $\bar{p}(t)$  are external pressure fluctuations.

# The method of characteristics

## The method of characteristics

In dimensionless form, the problem reads

$$\begin{aligned}v_t + p_x &= 0 \\ p_t + v_x &= 0\end{aligned}\quad \text{for } (x, t) \in ]0, 1[ \times ]0, \infty[ ,$$

with boundary conditions

$$\begin{aligned}\alpha v_t(0, t) + f(v(0, t)) + p(0, t) &= p_e + \bar{p}(t) \\ p(1, t) &= M v(1, t)\end{aligned}$$

## The method of characteristics

In dimensionless form, the problem reads

$$\begin{aligned}v_t + p_x &= 0 \\ p_t + v_x &= 0\end{aligned}\quad \text{for } (x, t) \in ]0, 1[ \times ]0, \infty[ ,$$

with boundary conditions

$$\begin{aligned}\alpha v_t(0, t) + f(v(0, t)) + p(0, t) &= p_e + \bar{p}(t) \\ p(1, t) &= M v(1, t)\end{aligned}$$

The solution is constructed recursively. In each time interval  $t \in [2k - 2, 2k]$ ,  $k = 1, 2, \dots$ , we find functions  $\varphi_k, \psi_k$  such that  $(v + p)(x, t) = \varphi_k(t - x)$ ,  $(v - p)(x, t) = \psi_k(t + x)$ .

## The method of characteristics

In dimensionless form, the problem reads

$$\begin{aligned}v_t + p_x &= 0 \\ p_t + v_x &= 0\end{aligned}\quad \text{for } (x, t) \in ]0, 1[ \times ]0, \infty[ ,$$

with boundary conditions

$$\begin{aligned}\alpha v_t(0, t) + f(v(0, t)) + p(0, t) &= p_e + \bar{p}(t) \\ p(1, t) &= M v(1, t)\end{aligned}$$

The solution is constructed recursively. In each time interval  $t \in [2k - 2, 2k]$ ,  $k = 1, 2, \dots$ , we find functions  $\varphi_k, \psi_k$  such that  $(v + p)(x, t) = \varphi_k(t - x)$ ,  $(v - p)(x, t) = \psi_k(t + x)$ . The problem is reduced to the ODE system

## The method of characteristics

In dimensionless form, the problem reads

$$\begin{aligned}v_t + p_x &= 0 \\ p_t + v_x &= 0\end{aligned}\quad \text{for } (x, t) \in ]0, 1[ \times ]0, \infty[ ,$$

with boundary conditions

$$\begin{aligned}\alpha v_t(0, t) + f(v(0, t)) + p(0, t) &= p_e + \bar{p}(t) \\ p(1, t) &= M v(1, t)\end{aligned}$$

The solution is constructed recursively. In each time interval  $t \in [2k - 2, 2k]$ ,  $k = 1, 2, \dots$ , we find functions  $\varphi_k, \psi_k$  such that  $(v + p)(x, t) = \varphi_k(t - x)$ ,  $(v - p)(x, t) = \psi_k(t + x)$ . The problem is reduced to the ODE system

$$\alpha \dot{v}_k(t) + g(v_k(t)) = \psi_k(t) + \bar{p}_k(t) \quad \text{for } t \in [0, 2]$$



## The method of characteristics

In dimensionless form, the problem reads

$$\begin{aligned}v_t + p_x &= 0 \\ p_t + v_x &= 0\end{aligned}\quad \text{for } (x, t) \in ]0, 1[ \times ]0, \infty[ ,$$

with boundary conditions

$$\begin{aligned}\alpha v_t(0, t) + f(v(0, t)) + p(0, t) &= p_e + \bar{p}(t) \\ p(1, t) &= M v(1, t)\end{aligned}$$

The solution is constructed recursively. In each time interval  $t \in [2k - 2, 2k]$ ,  $k = 1, 2, \dots$ , we find functions  $\varphi_k, \psi_k$  such that  $(v + p)(x, t) = \varphi_k(t - x)$ ,  $(v - p)(x, t) = \psi_k(t + x)$ . The problem is reduced to the ODE system

$$\begin{aligned}\alpha \dot{v}_k(t) + g(v_k(t)) &= \psi_k(t) + \bar{p}_k(t) \quad \text{for } t \in [0, 2] \\ \varphi_k &= 2v_k - \psi_k\end{aligned}$$

## The method of characteristics

In dimensionless form, the problem reads

$$\begin{aligned}v_t + p_x &= 0 \\ p_t + v_x &= 0\end{aligned}\quad \text{for } (x, t) \in ]0, 1[ \times ]0, \infty[ ,$$

with boundary conditions

$$\begin{aligned}\alpha v_t(0, t) + f(v(0, t)) + p(0, t) &= p_e + \bar{p}(t) \\ p(1, t) &= M v(1, t)\end{aligned}$$

The solution is constructed recursively. In each time interval  $t \in [2k - 2, 2k]$ ,  $k = 1, 2, \dots$ , we find functions  $\varphi_k, \psi_k$  such that  $(v + p)(x, t) = \varphi_k(t - x)$ ,  $(v - p)(x, t) = \psi_k(t + x)$ . The problem is reduced to the ODE system

$$\begin{aligned}\alpha \dot{v}_k(t) + g(v_k(t)) &= \psi_k(t) + \bar{p}_k(t) \quad \text{for } t \in [0, 2] \\ \varphi_k &= 2v_k - \psi_k \\ g(v) &= v + f(v) - p_e \quad \text{for } v \in \mathbb{R},\end{aligned}$$

## The method of characteristics

In dimensionless form, the problem reads

$$\begin{aligned}v_t + p_x &= 0 \\ p_t + v_x &= 0\end{aligned}\quad \text{for } (x, t) \in ]0, 1[ \times ]0, \infty[ ,$$

with boundary conditions

$$\begin{aligned}\alpha v_t(0, t) + f(v(0, t)) + p(0, t) &= p_e + \bar{p}(t) \\ p(1, t) &= M v(1, t)\end{aligned}$$

The solution is constructed recursively. In each time interval  $t \in [2k - 2, 2k]$ ,  $k = 1, 2, \dots$ , we find functions  $\varphi_k, \psi_k$  such that  $(v + p)(x, t) = \varphi_k(t - x)$ ,  $(v - p)(x, t) = \psi_k(t + x)$ . The problem is reduced to the ODE system

$$\begin{aligned}\alpha \dot{v}_k(t) + g(v_k(t)) &= \psi_k(t) + \bar{p}_k(t) \quad \text{for } t \in [0, 2] \\ \varphi_k &= 2v_k - \psi_k \\ g(v) &= v + f(v) - p_e \quad \text{for } y \in \mathbb{R}, \\ \psi_k(t) &= \frac{M - 1}{M + 1} (\psi_{k-1}(t) - 2v_{k-1}(t)).\end{aligned}$$

## Practical issue

## Practical issue

Engineers want to neglect the inertance and consider  $\alpha = 0$ , in order to investigate the long time behavior of the pump-valve system as a recurrent functional relation, without solving the sequence of differential equations.

## Practical issue

Engineers want to neglect the inertance and consider  $\alpha = 0$ , in order to investigate the long time behavior of the pump-valve system as a recurrent functional relation, without solving the sequence of differential equations.

To justify this procedure, we have to

- propose a selection rule in case of multiple solutions;

## Practical issue

Engineers want to neglect the inertance and consider  $\alpha = 0$ , in order to investigate the long time behavior of the pump-valve system as a recurrent functional relation, without solving the sequence of differential equations.

To justify this procedure, we have to

- propose a selection rule in case of multiple solutions;
- find a proper function space in which the convergence  $\alpha \rightarrow 0$  takes place;

## Practical issue

Engineers want to neglect the inertance and consider  $\alpha = 0$ , in order to investigate the long time behavior of the pump-valve system as a recurrent functional relation, without solving the sequence of differential equations.

To justify this procedure, we have to

- propose a selection rule in case of multiple solutions;
- find a proper function space in which the convergence  $\alpha \rightarrow 0$  takes place;
- define a suitable topology;



## Practical issue

Engineers want to neglect the inertance and consider  $\alpha = 0$ , in order to investigate the long time behavior of the pump-valve system as a recurrent functional relation, without solving the sequence of differential equations.

To justify this procedure, we have to

- propose a selection rule in case of multiple solutions;
- find a proper function space in which the convergence  $\alpha \rightarrow 0$  takes place;
- define a suitable topology;
- give rigorous convergence proofs.

## Practical issue

Engineers want to neglect the inertance and consider  $\alpha = 0$ , in order to investigate the long time behavior of the pump-valve system as a recurrent functional relation, without solving the sequence of differential equations.

To justify this procedure, we have to

- propose a selection rule in case of multiple solutions;
- find a proper function space in which the convergence  $\alpha \rightarrow 0$  takes place;
- define a suitable topology;
- give rigorous convergence proofs.

Neither the space  $C[0, T]$  of continuous functions, nor the space  $BV(0, T)$  of functions of bounded variation are the right choice.

## Functions of bounded variation

The space  $BV(0, T)$  of functions of bounded variation on an interval  $[0, T]$  contains all functions  $u : [0, T] \rightarrow X$  which admit a constant  $C > 0$  such that

$$\sum_{k=1}^m |u(t_k) - u(t_{k-1})| \leq C$$

for every division  $0 = t_0 < t_1 < \dots < t_m = T$  of  $[0, T]$ .

## Functions of bounded variation

The space  $BV(0, T)$  of functions of bounded variation on an interval  $[0, T]$  contains all functions  $u : [0, T] \rightarrow X$  which admit a constant  $C > 0$  such that

$$\sum_{k=1}^m |u(t_k) - u(t_{k-1})| \leq C$$

for every division  $0 = t_0 < t_1 < \dots < t_m = T$  of  $[0, T]$ .

Let  $\mathcal{D}_{0,T}$  be the set of all divisions of  $[0, T]$ . The number

$$\text{Var}_{[0,T]} u := \sup_{\mathcal{D}_{0,T}} \sum_{k=1}^m |u(t_k) - u(t_{k-1})|$$

is called the **total variation** of  $u$  on  $[0, T]$ .

## Helly selection principle

Let  $C > 0$  be a constant, and let  $u_n \in BV(0, T)$  for  $n \in \mathbb{N}$  be a sequence such that

$$|u_n(0)| + \operatorname{Var}_{[0, T]} u_n \leq C.$$

Then there exists a subsequence  $\{u_{n_k}\}$  of  $\{u_n\}$  and a function  $u \in BV(0, T)$  such that  $u_{n_k}(t) \rightarrow u(t)$  for  $k \rightarrow \infty$  for all  $t \in [0, T]$ .

## Helly selection principle

Let  $C > 0$  be a constant, and let  $u_n \in BV(0, T)$  for  $n \in \mathbb{N}$  be a sequence such that

$$|u_n(0)| + \operatorname{Var}_{[0, T]} u_n \leq C.$$

Then there exists a subsequence  $\{u_{n_k}\}$  of  $\{u_n\}$  and a function  $u \in BV(0, T)$  such that  $u_{n_k}(t) \rightarrow u(t)$  for  $k \rightarrow \infty$  for all  $t \in [0, T]$ .

**Extensions** exist in the space of the so-called **functions of bounded  $p$ -variation**  $BV_p(0, T) = \{f : [0, T] \rightarrow \mathbb{R}; p\text{-Var}_{[0, T]} f < \infty\}$  for  $p > 1$ , where

$$p\text{-Var}_{[0, T]} f := \sup_{\mathcal{D}_{0, T}} \sum_{k=1}^m |f(t_k) - f(t_{k-1})|^p.$$

(Chistyakov and Galkin (1998), J. E. Porter (2005)).

## Functions of bounded $\varphi$ -variation

More generally, for an arbitrary convex function  $\varphi : [0, \infty[ \rightarrow [0, \infty[$  such that  $\varphi(0) = 0$ , we define the  $\varphi$ -variation of  $f : [0, T] \rightarrow \mathbb{R}$  as

$$\varphi\text{-Var } f := \sup_{\mathcal{D}_{0,T}} \sum_{k=1}^m \varphi(|f(t_k) - f(t_{k-1})|),$$

and denote  $BV_{\varphi}(0, T) = \{f : [0, T] \rightarrow \mathbb{R}; \varphi\text{-Var } f < \infty\}$ .

## Functions of bounded $\varphi$ -variation

More generally, for an arbitrary convex function  $\varphi : [0, \infty[ \rightarrow [0, \infty[$  such that  $\varphi(0) = 0$ , we define the  $\varphi$ -variation of  $f : [0, T] \rightarrow \mathbb{R}$  as

$$\varphi\text{-Var } f := \sup_{\mathcal{D}_{0,T}} \sum_{k=1}^m \varphi(|f(t_k) - f(t_{k-1})|),$$

and denote  $BV_{\varphi}(0, T) = \{f : [0, T] \rightarrow \mathbb{R}; \varphi\text{-Var } f < \infty\}$ .

Clearly, the right and left limits  $f(t+), f(t-)$  exist for all  $\varphi$ , all  $f \in BV_{\varphi}(0, T)$ , and all  $t \in [0, T]$ , with the convention  $f(0-) = f(0), f(T+) = f(T)$ .



## Regulated functions

A function  $f : [0, T] \rightarrow \mathbb{R}$  is said to be **regulated**, if the right and left limits  $f(t+)$ ,  $f(t-)$  exist for all  $t \in [0, T]$ .

We denote the set of all regulated functions  $f : [0, T] \rightarrow \mathbb{R}$  by the symbol  $G(0, T)$ . With the norm

$$\|f\|_{\infty} = \sup_{t \in [0, T]} |f(t)|,$$

$G(0, T)$  is a **Banach space**,

## Regulated functions

A function  $f : [0, T] \rightarrow \mathbb{R}$  is said to be **regulated**, if the right and left limits  $f(t+)$ ,  $f(t-)$  exist for all  $t \in [0, T]$ .

We denote the set of all regulated functions  $f : [0, T] \rightarrow \mathbb{R}$  by the symbol  $G(0, T)$ . With the norm

$$\|f\|_{\infty} = \sup_{t \in [0, T]} |f(t)|,$$

$G(0, T)$  is a **Banach space**, with the following properties:

## Regulated functions

A function  $f : [0, T] \rightarrow \mathbb{R}$  is said to be **regulated**, if the right and left limits  $f(t+), f(t-)$  exist for all  $t \in [0, T]$ .

We denote the set of all regulated functions  $f : [0, T] \rightarrow \mathbb{R}$  by the symbol  $G(0, T)$ . With the norm

$$\|f\|_{\infty} = \sup_{t \in [0, T]} |f(t)|,$$

$G(0, T)$  is a **Banach space**, with the following properties:

- $BV(0, T) \subset G(0, T)$  is a dense subspace;

## Regulated functions

A function  $f : [0, T] \rightarrow \mathbb{R}$  is said to be **regulated**, if the right and left limits  $f(t+), f(t-)$  exist for all  $t \in [0, T]$ .

We denote the set of all regulated functions  $f : [0, T] \rightarrow \mathbb{R}$  by the symbol  $G(0, T)$ . With the norm

$$\|f\|_{\infty} = \sup_{t \in [0, T]} |f(t)|,$$

$G(0, T)$  is a **Banach space**, with the following properties:

- $BV(0, T) \subset G(0, T)$  is a dense subspace;
- $C([0, T]) \subset G(0, T)$  is a closed subspace;

## Regulated functions

A function  $f : [0, T] \rightarrow \mathbb{R}$  is said to be **regulated**, if the right and left limits  $f(t+), f(t-)$  exist for all  $t \in [0, T]$ .

We denote the set of all regulated functions  $f : [0, T] \rightarrow \mathbb{R}$  by the symbol  $G(0, T)$ . With the norm

$$\|f\|_{\infty} = \sup_{t \in [0, T]} |f(t)|,$$

$G(0, T)$  is a **Banach space**, with the following properties:

- $BV(0, T) \subset G(0, T)$  is a dense subspace;
- $C([0, T]) \subset G(0, T)$  is a closed subspace;
- $G(0, T) = \bigcup_{\varphi} BV_{\varphi}(0, T)$ ;

## Regulated functions

A function  $f : [0, T] \rightarrow \mathbb{R}$  is said to be **regulated**, if the right and left limits  $f(t+), f(t-)$  exist for all  $t \in [0, T]$ .

We denote the set of all regulated functions  $f : [0, T] \rightarrow \mathbb{R}$  by the symbol  $G(0, T)$ . With the norm

$$\|f\|_{\infty} = \sup_{t \in [0, T]} |f(t)|,$$

$G(0, T)$  is a **Banach space**, with the following properties:

- $BV(0, T) \subset G(0, T)$  is a dense subspace;
- $C([0, T]) \subset G(0, T)$  is a closed subspace;
- $G(0, T) = \bigcup_{\varphi} BV_{\varphi}(0, T)$ ;

The Helly selection principle **does not hold** in  $G(0, T)$ !

**Example:**  $f_n(t) = \sin nt$  for  $t \in [0, \pi]$ .

## The Fraňková Theorem (1991)

Let  $f_n \in G(0, T)$  for  $n \in \mathbb{N}$  be a sequence with the property

$$\forall \varepsilon > 0 \quad \exists L_\varepsilon > 0 \quad \forall n \in \mathbb{N} \quad \exists u_n \in BV(0, T) :$$

$$\|u_n - f_n\|_\infty < \varepsilon, \quad |u_n(0)| + \operatorname{Var}_{[0, T]} u_n \leq L_\varepsilon.$$

Then there exists a subsequence  $\{f_{n_k}\}$  of  $\{f_n\}$  and a function  $f \in G(0, T)$  such that  $f_{n_k}(t) \rightarrow f(t)$  for  $k \rightarrow \infty$  for all  $t \in [0, T]$ .

## The Fraňková Theorem (1991)

Let  $f_n \in G(0, T)$  for  $n \in \mathbb{N}$  be a sequence with the property

$$\forall \varepsilon > 0 \quad \exists L_\varepsilon > 0 \quad \forall n \in \mathbb{N} \quad \exists u_n \in BV(0, T) :$$

$$\|u_n - f_n\|_\infty < \varepsilon, \quad |u_n(0)| + \operatorname{Var}_{[0, T]} u_n \leq L_\varepsilon.$$

Then there exists a subsequence  $\{f_{n_k}\}$  of  $\{f_n\}$  and a function  $f \in G(0, T)$  such that  $f_{n_k}(t) \rightarrow f(t)$  for  $k \rightarrow \infty$  for all  $t \in [0, T]$ .

**Question:** A criterion to check the condition of bounded  $\varepsilon$ -variation?



## The Fraňková Theorem (1991)

Let  $f_n \in G(0, T)$  for  $n \in \mathbb{N}$  be a sequence with the property

$$\forall \varepsilon > 0 \quad \exists L_\varepsilon > 0 \quad \forall n \in \mathbb{N} \quad \exists u_n \in BV(0, T) :$$

$$\|u_n - f_n\|_\infty < \varepsilon, \quad |u_n(0)| + \operatorname{Var}_{[0, T]} u_n \leq L_\varepsilon.$$

Then there exists a subsequence  $\{f_{n_k}\}$  of  $\{f_n\}$  and a function  $f \in G(0, T)$  such that  $f_{n_k}(t) \rightarrow f(t)$  for  $k \rightarrow \infty$  for all  $t \in [0, T]$ .

**Question:** A criterion to check the condition of bounded  $\varepsilon$ -variation?

It is necessary to approximate regulated functions uniformly by  $BV$ -functions, keeping the total variations of the approximations uniformly bounded and depending only on  $\varepsilon$ .

# Variational inequality

## Variational inequality

A standard way to approximate a function  $f$  of unbounded variation by a function  $u \in BV(0, T)$  consists in solving the differential inclusion

$$\dot{u}(t) \in \partial I_{[-\varepsilon, \varepsilon]}(f(t) - u(t)), \quad u(0) = f(0),$$

where  $I_{[-\varepsilon, \varepsilon]}$  is the indicator function of  $[-\varepsilon, \varepsilon]$ , and  $\partial$  is the symbol for the subdifferential.

## Variational inequality

A standard way to approximate a function  $f$  of unbounded variation by a function  $u \in BV(0, T)$  consists in solving the differential inclusion

$$\dot{u}(t) \in \partial I_{[-\varepsilon, \varepsilon]}(f(t) - u(t)), \quad u(0) = f(0),$$

where  $I_{[-\varepsilon, \varepsilon]}$  is the indicator function of  $[-\varepsilon, \varepsilon]$ , and  $\partial$  is the symbol for the subdifferential. The mapping that with  $f$  associates  $u$  is called the **play operator**.

## Variational inequality

A standard way to approximate a function  $f$  of unbounded variation by a function  $u \in BV(0, T)$  consists in solving the differential inclusion

$$\dot{u}(t) \in \partial I_{[-\varepsilon, \varepsilon]}(f(t) - u(t)), \quad u(0) = f(0),$$

where  $I_{[-\varepsilon, \varepsilon]}$  is the indicator function of  $[-\varepsilon, \varepsilon]$ , and  $\partial$  is the symbol for the subdifferential. The mapping that with  $f$  associates  $u$  is called the **play operator**.

This inclusion is formally equivalent to the variational inequality

$$\|f - u\|_{\infty} \leq \varepsilon, \quad \dot{u}(t)(f(t) - u(t) - z) \geq 0 \quad \forall z \in [-\varepsilon, \varepsilon],$$

## Variational inequality

A standard way to approximate a function  $f$  of unbounded variation by a function  $u \in BV(0, T)$  consists in solving the differential inclusion

$$\dot{u}(t) \in \partial I_{[-\varepsilon, \varepsilon]}(f(t) - u(t)), \quad u(0) = f(0),$$

where  $I_{[-\varepsilon, \varepsilon]}$  is the indicator function of  $[-\varepsilon, \varepsilon]$ , and  $\partial$  is the symbol for the subdifferential. The mapping that with  $f$  associates  $u$  is called the **play operator**.

This inclusion is formally equivalent to the variational inequality

$$\|f - u\|_\infty \leq \varepsilon, \quad \dot{u}(t)(f(t) - u(t) - z) \geq 0 \quad \forall z \in [-\varepsilon, \varepsilon],$$

which we have to reformulate in terms of the **Kurzweil integral**

$$\|f - u\|_\infty \leq \varepsilon, \quad \int_0^t (f(\tau+) - u(\tau+) - z(\tau)) du(\tau) \geq 0 \\ \forall z \in G(0, T; [-\varepsilon, \varepsilon]) \quad \forall t \in [0, T].$$

# Kurzweil variational inequality

## Kurzweil variational inequality

Given a function  $f \in G(0, T)$ , we look for  $u \in BV(0, T)$  such that  $u(0) = f(0)$ , and

$$\|f - u\|_\infty \leq \varepsilon, \quad \int_0^t (f(\tau+) - u(\tau+) - z(\tau)) du(\tau) \geq 0$$
$$\forall z \in G(0, T; [-\varepsilon, \varepsilon]) \quad \forall t \in [0, T].$$

In this generality, the problem is uniquely solvable **if and only if** we admit functions  $u$  with **bounded essential variation**.



## Kurzweil variational inequality

Given a function  $f \in G(0, T)$ , we look for  $u \in BV(0, T)$  such that  $u(0) = f(0)$ , and

$$\|f - u\|_\infty \leq \varepsilon, \quad \int_0^t (f(\tau+) - u(\tau+) - z(\tau)) du(\tau) \geq 0 \\ \forall z \in G(0, T; [-\varepsilon, \varepsilon]) \quad \forall t \in [0, T].$$

In this generality, the problem is uniquely solvable **if and only if** we admit functions  $u$  with **bounded essential variation**.

Isolated singularities (i.e. points where  $f(t)$  differs from both  $f(t+)$  and  $f(t-)$ ) have no influence on future evolution and **can be removed**. Hence, we can restrict ourselves e.g. to variational inequalities with **left continuous** inputs  $f \in G_L(0, T)$

$$\int_0^T (f(\tau+) - u(\tau+) - z(\tau)) du(\tau) \geq 0 \quad \forall z \in G(0, T; [-\varepsilon, \varepsilon])$$

which admits a unique **left continuous** solution  $u \in BV_L(0, T)$ .

# Relation between Kurzweil variational inequalities and $\varphi$ -variation

## Relation between Kurzweil variational inequalities and $\varphi$ -variation

**Theorem 1.** *Let a set  $F \subset G_L(0, T)$  and  $\varepsilon > 0$  be given. Let there exist a convex increasing function  $\varphi$  and a constant  $C_F > 0$  such that*

$$\forall f \in F : \varphi\text{-Var } f \leq C_F.$$

*The the set  $U_F$  of all solutions  $u$  of the Kurzweil variational inequality with inputs  $f \in F$  has uniformly bounded variation.*

## Relation between Kurzweil variational inequalities and $\varphi$ -variation

**Theorem 1.** *Let a set  $F \subset G_L(0, T)$  and  $\varepsilon > 0$  be given. Let there exist a convex increasing function  $\varphi$  and a constant  $C_F > 0$  such that*

$$\forall f \in F : \varphi\text{-Var } f \leq C_F.$$

*The set  $U_F$  of all solutions  $u$  of the Kurzweil variational inequality with inputs  $f \in F$  has uniformly bounded variation.*

Hence, functions of bounded  $\varphi$ -variation satisfy the  $\varepsilon$ -condition in the Fraňková Theorem.

## Relation between Kurzweil variational inequalities and $\varphi$ -variation

**Theorem 1.** *Let a set  $F \subset G_L(0, T)$  and  $\varepsilon > 0$  be given. Let there exist a convex increasing function  $\varphi$  and a constant  $C_F > 0$  such that*

$$\forall f \in F : \varphi\text{-Var } f \leq C_F.$$

*The set  $U_F$  of all solutions  $u$  of the Kurzweil variational inequality with inputs  $f \in F$  has uniformly bounded variation.*

Hence, functions of bounded  $\varphi$ -variation satisfy the  $\varepsilon$ -condition in the Fraňková Theorem.

**Corollary.** *For every function  $\varphi$ , the Helly selection principle holds in  $BV_\varphi(0, T)$ .*

## Relation between Kurzweil variational inequalities and $\varphi$ -variation

**Theorem 1.** Let a set  $F \subset G_L(0, T)$  and  $\varepsilon > 0$  be given. Let there exist a convex increasing function  $\varphi$  and a constant  $C_F > 0$  such that

$$\forall f \in F : \varphi\text{-Var } f \leq C_F.$$

The set  $U_F$  of all solutions  $u$  of the Kurzweil variational inequality with inputs  $f \in F$  has uniformly bounded variation.

Hence, functions of bounded  $\varphi$ -variation satisfy the  $\varepsilon$ -condition in the Fraňková Theorem.

**Corollary.** For every function  $\varphi$ , the Helly selection principle holds in  $BV_\varphi(0, T)$ .

**Theorem 2.** A set  $F \subset G(0, T)$  has uniformly bounded  $\varphi$ -variation for some function  $\varphi$  if and only if it has uniformly bounded oscillation: For each  $\varepsilon > 0$  there exists  $N_{F,\varepsilon} > 0$  such that if  $n$  disjoint intervals  $]a_k, b_k[$  satisfy the inequality  $|f(b_k) - f(a_k)| > \varepsilon$  for some function  $f \in F$ , then  $n \leq N_{F,\varepsilon}$ .

# *BO*-convergence

## BO-convergence

**Definition.** We say that a sequence  $f_n$  of functions from  $G(0, T)$  BO-converges to  $f \in G(0, T)$ , if the set  $\{f_n : n \in \mathbb{N}\}$  has uniformly bounded oscillation, and  $f_n(t) \rightarrow f(t)$  for all  $t \in [0, T]$ .



## *BO*-convergence

**Definition.** We say that a sequence  $f_n$  of functions from  $G(0, T)$  *BO*-converges to  $f \in G(0, T)$ , if the set  $\{f_n : n \in \mathbb{N}\}$  has uniformly bounded oscillation, and  $f_n(t) \rightarrow f(t)$  for all  $t \in [0, T]$ .

The following convergence theorem for the Kurzweil integral shows that the *BO*-convergence is a kind of **weak convergence** in  $G(0, T)$ .

## BO-convergence

**Definition.** We say that a sequence  $f_n$  of functions from  $G(0, T)$  BO-converges to  $f \in G(0, T)$ , if the set  $\{f_n : n \in \mathbb{N}\}$  has uniformly bounded oscillation, and  $f_n(t) \rightarrow f(t)$  for all  $t \in [0, T]$ .

The following convergence theorem for the Kurzweil integral shows that the BO-convergence is a kind of **weak convergence** in  $G(0, T)$ .

**Theorem 3.** Let  $f_n, f \in G(0, T)$ ,  $f_n(t) \rightarrow f(t)$  for all  $t \in [0, T]$ . Then the following two conditions are equivalent:

## BO-convergence

**Definition.** We say that a sequence  $f_n$  of functions from  $G(0, T)$  BO-converges to  $f \in G(0, T)$ , if the set  $\{f_n : n \in \mathbb{N}\}$  has uniformly bounded oscillation, and  $f_n(t) \rightarrow f(t)$  for all  $t \in [0, T]$ .

The following convergence theorem for the Kurzweil integral shows that the BO-convergence is a kind of **weak convergence** in  $G(0, T)$ .

**Theorem 3.** Let  $f_n, f \in G(0, T)$ ,  $f_n(t) \rightarrow f(t)$  for all  $t \in [0, T]$ . Then the following two conditions are equivalent:

- $f_n$  have uniformly bounded oscillation;

## BO-convergence

**Definition.** We say that a sequence  $f_n$  of functions from  $G(0, T)$  BO-converges to  $f \in G(0, T)$ , if the set  $\{f_n : n \in \mathbb{N}\}$  has uniformly bounded oscillation, and  $f_n(t) \rightarrow f(t)$  for all  $t \in [0, T]$ .

The following convergence theorem for the Kurzweil integral shows that the BO-convergence is a kind of **weak convergence** in  $G(0, T)$ .

**Theorem 3.** Let  $f_n, f \in G(0, T)$ ,  $f_n(t) \rightarrow f(t)$  for all  $t \in [0, T]$ . Then the following two conditions are equivalent:

- $f_n$  have uniformly bounded oscillation;
- for each sequence  $g_n \in BV(0, T)$  such that  $\text{Var}_{[0, T]} g_n \leq C$  a  $g_n \rightarrow g$  uniformly, we have

$$\int_0^T f_n(t) dg_n(t) \rightarrow \int_0^T f(t) dg(t).$$

## Bounded linear functionals on $G_L(0, T)$ a $G_R(0, T)$

## Bounded linear functionals on $G_L(0, T)$ a $G_R(0, T)$

**Theorem 4** (Hönig; Tvrdý; Brokate and Krejčí). *With each bounded linear functionals  $P_L$  on  $G_L(0, T)$  and  $P_R$  on  $G_R(0, T)$  we can associate uniquely determined functions  $g_L, g_R \in BV(0, T)$  such that*

$$P_L(f) = g_L(T)f(T) - \int_0^T g_L(t) df(t) \quad \forall f \in G_L(0, T),$$

$$P_R(f) = g_R(0)f(0) + \int_0^T g_R(t) df(t) \quad \forall f \in G_R(0, T),$$

*with the properties*

$$\|P_L\| = |g_L(0)| + \text{Var}_{[0, T]} g_L, \quad \|P_R\| = |g_R(T)| + \text{Var}_{[0, T]} g_R.$$

## Bounded linear functionals on $G_L(0, T)$ a $G_R(0, T)$

**Theorem 4** (Hönig; Tvrdý; Brokate and Krejčí). *With each bounded linear functionals  $P_L$  on  $G_L(0, T)$  and  $P_R$  on  $G_R(0, T)$  we can associate uniquely determined functions  $g_L, g_R \in BV(0, T)$  such that*

$$P_L(f) = g_L(T)f(T) - \int_0^T g_L(t) df(t) \quad \forall f \in G_L(0, T),$$

$$P_R(f) = g_R(0)f(0) + \int_0^T g_R(t) df(t) \quad \forall f \in G_R(0, T),$$

*with the properties*

$$\|P_L\| = |g_L(0)| + \text{Var}_{[0, T]} g_L, \quad \|P_R\| = |g_R(T)| + \text{Var}_{[0, T]} g_R.$$

**Corollary.** *The dual spaces to  $G_L(0, T)$ ,  $G_R(0, T)$  are both isometrically isomorphic to  $BV(0, T)$ .*

## Relation between weak convergence and $BO$ -convergence in $G_L(0, T)$



## Relation between weak convergence and $BO$ -convergence in $G_L(0, T)$

- If  $f_n \rightarrow f$  uniformly, then they converge both weakly and  $BO$ .

## Relation between weak convergence and $BO$ -convergence in $G_L(0, T)$

- If  $f_n \rightarrow f$  uniformly, then they converge both weakly and  $BO$ .
- The sequence

$$f_n(t) = \chi_{]0, 1/n]}(t)$$

in  $G_L(0, T)$   $BO$ -converges, but does not converge weakly;

## Relation between weak convergence and $BO$ -convergence in $G_L(0, T)$

- If  $f_n \rightarrow f$  uniformly, then they converge both weakly and  $BO$ .
- The sequence

$$f_n(t) = \chi_{]0, 1/n]}(t)$$

in  $G_L(0, T)$   $BO$ -converges, but does not converge weakly;

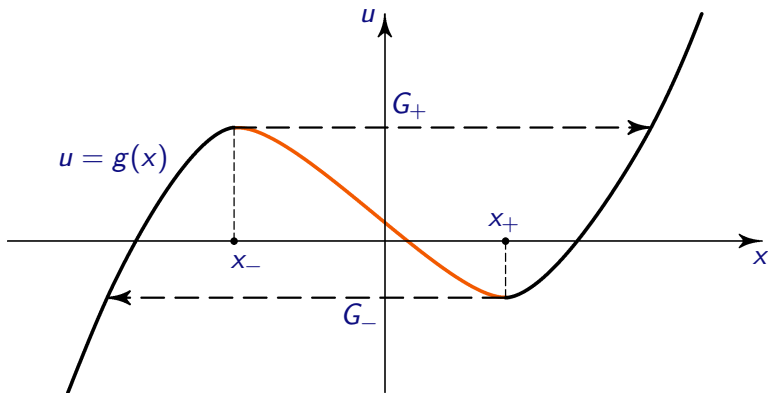
- Let  $b_1 > a_1 > b_2 > a_2 > \dots > 0$  be an infinite sequence of positive numbers. The sequence

$$f_n(t) = \sum_{k=n}^{2n} \chi_{]a_k, b_k]}(t)$$

converges weakly in  $G_L(0, T)$ , but does not have bounded oscillation.

## Back to a singularly perturbed problem

$$\alpha \dot{x}(t) + g(x(t)) = u(t), \quad x(0) = x_0$$



## Uniformly bounded oscillation in singularly perturbed systems

## Uniformly bounded oscillation in singularly perturbed systems

**Theorem 5.** *Let  $U \subset G_L[0, T]$  be a bounded set with uniformly bounded oscillation, and let  $c > 0$  be a constant. Then the set  $X \subset W^{1,\infty}[0, T]$  of all solutions  $x$  to*

$$\alpha \dot{x}(t) + g(x(t)) = u(t), \quad x(0) = x_0$$

*with  $u \in U$ ,  $x_0 \in [-c, c]$ , and  $\alpha > 0$  is bounded and has uniformly bounded oscillation.*

## Uniformly bounded oscillation in singularly perturbed systems

**Theorem 5.** *Let  $U \subset G_L[0, T]$  be a bounded set with uniformly bounded oscillation, and let  $c > 0$  be a constant. Then the set  $X \subset W^{1,\infty}[0, T]$  of all solutions  $x$  to*

$$\alpha \dot{x}(t) + g(x(t)) = u(t), \quad x(0) = x_0$$

*with  $u \in U$ ,  $x_0 \in [-c, c]$ , and  $\alpha > 0$  is bounded and has uniformly bounded oscillation.*

In the proof, the **play operator** is used in a substantial way.

## Convergence in singularly perturbed systems



## Convergence in singularly perturbed systems

**Theorem 6.** Let  $u \in G_L(0, T)$  and  $x_0 \in \mathbb{R}$  be given. Assume that one of the following two conditions holds:

- (i)  $x_0 \notin ]x_-, x_+[$ .
- (ii)  $x_0 \in ]x_-, x_+[$ ,  $u(0+) \neq g(x_0)$ .

Then there exists a function  $x \in G_L(0, T)$  such that  $x(t) \notin ]x_-, x_+[$  and  $g(x(t)) = u(t)$  for every  $t \in ]0, T]$ , and  $x_\alpha$  BO-converge to  $x$ .

## Convergence in singularly perturbed systems

**Theorem 6.** Let  $u \in G_L(0, T)$  and  $x_0 \in \mathbb{R}$  be given. Assume that one of the following two conditions holds:

- (i)  $x_0 \notin ]x_-, x_+[$ .
- (ii)  $x_0 \in ]x_-, x_+[$ ,  $u(0+) \neq g(x_0)$ .

Then there exists a function  $x \in G_L(0, T)$  such that  $x(t) \notin ]x_-, x_+[$  and  $g(x(t)) = u(t)$  for every  $t \in ]0, T]$ , and  $x_\alpha$  BO-converge to  $x$ .

The choice of  $x(t)$  in the multivalued relation  $g(x(t)) = u(t)$  corresponds to the *maximal hysteresis rule*.

## Convergence in singularly perturbed systems

**Theorem 6.** Let  $u \in G_L(0, T)$  and  $x_0 \in \mathbb{R}$  be given. Assume that one of the following two conditions holds:

- (i)  $x_0 \notin ]x_-, x_+[$ .
- (ii)  $x_0 \in ]x_-, x_+[$ ,  $u(0+) \neq g(x_0)$ .

Then there exists a function  $x \in G_L(0, T)$  such that  $x(t) \notin ]x_-, x_+[$  and  $g(x(t)) = u(t)$  for every  $t \in ]0, T]$ , and  $x_\alpha$  BO-converge to  $x$ .

The choice of  $x(t)$  in the multivalued relation  $g(x(t)) = u(t)$  corresponds to the *maximal hysteresis rule*.

If  $x_0 \in ]x_-, x_+[$ ,  $u(0+) = g(x_0)$ , then the subset  $Y$  of

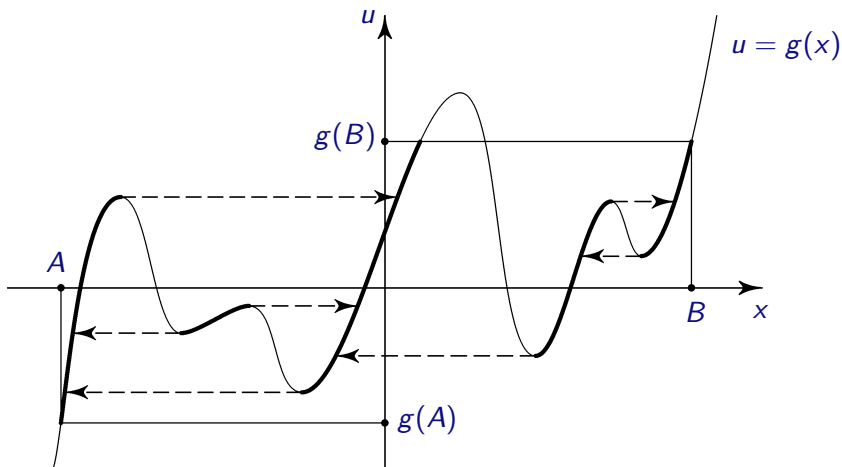
$$U = \{\hat{u} \in G_L(0, T) : \hat{u}(0+) = u(0+), \hat{u}(t) \in [G_-, G_+] \forall t \in [0, T]\}$$

containing all right hand sides for which  $x_\alpha(t)$  do not converge for any subsequence  $\alpha_j \rightarrow 0$ , is of the second Baire category.

## More general nonlinearities

## More general nonlinearities

Similar statements hold for a large class of nonlinearities.



## Conclusions

- The space of regulated function has a very rich topological structure: uniform convergence, weak convergence,  $BO$ -convergence.

## Conclusions

- The space of regulated function has a very rich topological structure: uniform convergence, weak convergence,  $BO$ -convergence.
- The play operator defined as the solution operator of a Kurzweil integral variational inequality transforms regulated functions into  $BV$ -functions, and sets with uniformly bounded oscillation into sets with uniformly bounded variation.

## Conclusions

- The space of regulated function has a very rich topological structure: uniform convergence, weak convergence,  $BO$ -convergence.
- The play operator defined as the solution operator of a Kurzweil integral variational inequality transforms regulated functions into  $BV$ -functions, and sets with uniformly bounded oscillation into sets with uniformly bounded variation.
- In bounded sets with uniformly bounded oscillation, the Fraňková extension of the Helly selection principle holds.



## Conclusions

- The space of regulated function has a very rich topological structure: uniform convergence, weak convergence,  $BO$ -convergence.
- The play operator defined as the solution operator of a Kurzweil integral variational inequality transforms regulated functions into  $BV$ -functions, and sets with uniformly bounded oscillation into sets with uniformly bounded variation.
- In bounded sets with uniformly bounded oscillation, the Fraňková extension of the Helly selection principle holds.
- Solutions of differential equations with a singular parameter in front of the derivative  $BO$ -converge to a rate independent hysteresis relation on a non-monotone graph.