1. Introduction

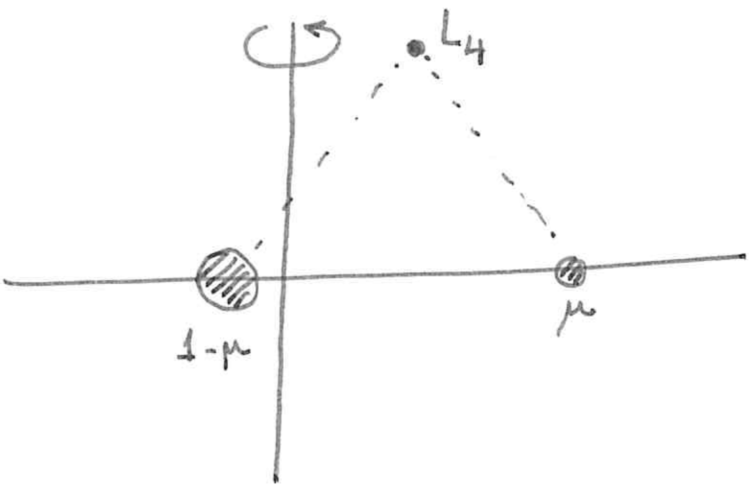
Consider a Hamiltonian system with two degrees of freedom

$$(*) \qquad \dot{q}_i = \frac{\partial H}{\partial p_i}, \quad \dot{p}_i = -\frac{\partial H}{\partial q_i}, \quad i = 1,2$$

where $H = H(q,p)$ is a smooth function defined on $\Omega \subset \mathbb{R}^2 \times \mathbb{R}^2$.

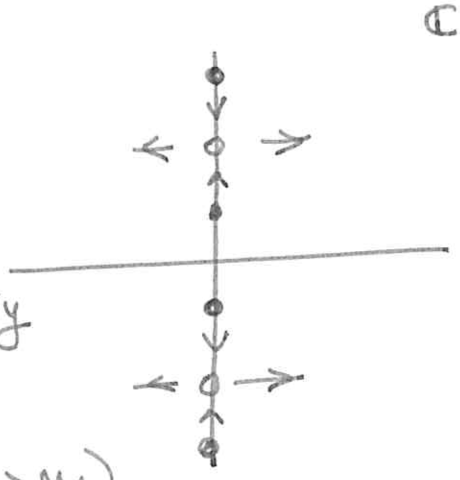
The study of periodic solutions (existence and stability) is an old problem (≥ 120 years). There are many results but most of the results dealing with stability are either local (small parameters) or use the computer. We are interested in non-local stability results.

The prototype can be the stability of the libration point L_4 in the circular restricted three body problem



The primaries have masses $1-\mu$ and μ with $\mu \in]0, \frac{1}{2}]$. The whole plane is rotating around the vertical axis and the satellite is placed at the vertex of an equilateral triangle composed by the three bodies. Note that in the rotating system L_4 is an equilibrium but in the inertial system it is a periodic solution. In this case the periodic solution is known explicitly and the linearized system is autonomous and can be solved. For linearized stability we find the necessary and sufficient condition

$$0 < \mu < \mu_1 = \frac{1}{2}\left(1 - \frac{\sqrt{69}}{9}\right)$$



the eigenvalues lie on the imaginary axis ($\mu < \mu_1$), then collide ($\mu = \mu_1$) and then get out of this axis ($\mu > \mu_1$).

For nonlinear stability there exist two numbers $0 < \mu_3 < \mu_2 < \mu_1$ which can be computed and such that L_4 is stable (in the Lyapunov sense) if and only if

$$0 < \mu \leq \mu_1 \quad \text{and} \quad \mu \neq \mu_2, \mu_3 .$$

The nonlinear analysis is very delicate and the proof was obtained once KAM theory was available (see [MHO] for more details).

The purpose of this course is to develop some tools which can be useful to study more general non-local stability problems. Ideally I would like to apply these tools to the general case (*) but by now I can only deal with a special family: periodic systems with one degree of freedom. That is,

$$H = H(t,q,p), \quad q,p \in \mathbb{R}, \quad H(t+2\pi, q, p) = H(t,q,p)$$

$$(**) \qquad \dot{q} = \frac{\partial H}{\partial p}, \quad \dot{p} = -\frac{\partial H}{\partial q}.$$

This system can be immersed in the larger family (*) by introducing new variables

$$Q = t, \quad \mathcal{P} = H, \quad \mathcal{H}(q, Q, p, \mathcal{P}) = H(Q, q, p) + \mathcal{P}.$$

The periodicity of time allows us to interpret Q as an angular variable $\left(Q \in \mathbb{T} = \mathbb{R}/_{2\pi \mathbb{Z}} \right)$,

$$\begin{cases} \dot{q} = \dfrac{\partial \mathcal{H}}{\partial p} = \dfrac{\partial H}{\partial p}, & \dot{p} = -\dfrac{\partial \mathcal{H}}{\partial q} = -\dfrac{\partial H}{\partial q} \\[2ex] \dot{Q} = \dfrac{\partial \mathcal{H}}{\partial \mathcal{P}} = 1, & \dot{\mathcal{P}} = -\dfrac{\partial \mathcal{H}}{\partial Q} = -\dfrac{\partial H}{\partial t} \end{cases}$$

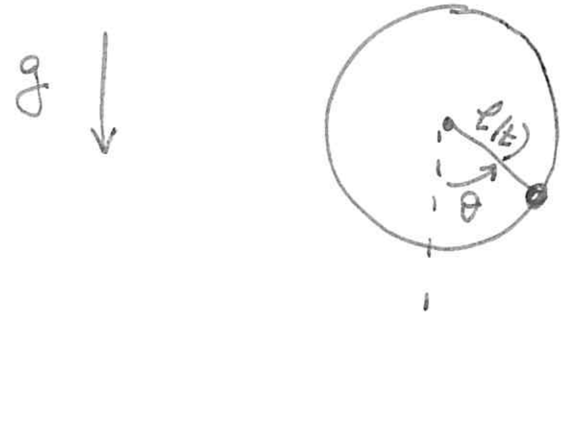
At each energy level $\mathcal{H} = $ constant, the dynamics of (**) is repeated. Let us now see some non-local results for (**).

1.1. The pendulum of variable length

Consider the equation

$$\text{(VLP)} \qquad \ddot{\theta} + \alpha(t) \sin\theta = 0$$

where α is 2π-periodic and positive. After a change of the independent variable this is the equation of a particle moving on a pulsating circle $\left(\alpha(t) = g\, \ell(t)^3 \right)$ under the action of gravity.



The stability of the equilibrium $\theta = 0$ for small parameters $\left(\alpha(t) = \omega^2 + \varepsilon p(t)\right)$, $\omega \neq n, n+\frac{1}{2}$, $n = 0, 1, 2\ldots$ is a typical illustration of KAM theory (see the book [AA]). We are interested in the non-local problem with

$$\alpha \in C(\mathbb{T}), \quad \min \alpha(t) > 0 .$$

Again the periodic solution is explicitly known $(\theta = 0)$ but now the linearized equation

$$\text{(LVLP)} \qquad \ddot{y} + \alpha(t) y = 0$$

cannot be solved explicitly. As we will see this linear equation contains all the information about the stability of $\theta = 0$ if we exploit the symplectic structure. To explain the result we make our first digression on the symplectic group.

The group $Sp(\mathbb{R}^2)$ is composed by the 2×2 matrices A satisfying

$$\det A = 1 .$$

Associated to this group we have a notion of conjugate matrices, $A \sim B$ if there exists $P \in Sp(\mathbb{R}^2)$ such that $A = PBP^{-1}$. The conjugacy classes in $Sp(\mathbb{R}^2)$ are

$$R[\theta] = \begin{pmatrix} \cos\theta & -\sin\theta \\ \sin\theta & \cos\theta \end{pmatrix}, \quad \theta \in [0, 2\pi[$$

$$H_{\pm}[\theta] = \begin{pmatrix} \pm \operatorname{ch}\theta & \operatorname{sh}\theta \\ \operatorname{sh}\theta & \pm \operatorname{ch}\theta \end{pmatrix}, \quad \theta > 0$$

$$P_+ = \begin{pmatrix} 1 & 1 \\ 0 & 1 \end{pmatrix}, \quad P_- = \begin{pmatrix} 1 & -1 \\ 0 & 1 \end{pmatrix}, \quad -P_+, \quad -P_-.$$

Note that there are matrices which are conjugate in $Gl(\mathbb{R}^2)$ but not in $Sp(\mathbb{R}^2)$,

$R[\theta] \not\sim R[-\theta]$ in $Sp(\mathbb{R}^2)$, $\theta \neq 0, \pi$

$R[\theta] \sim R[-\theta]$ in $Gl(\mathbb{R}^2)$

$P_+ \not\sim P_-$ in $Sp(\mathbb{R}^2)$ but $P_+ \sim P_-$ in $Gl(\mathbb{R}^2)$...

We can now state the characterization of stability for $\theta = 0$. Let M be the monodromy matrix of (LVLP), then

$\theta = 0$ is linearly stable if and only if $M \sim R[\theta]$ in $Sp(\mathbb{R}^2)$ for some θ

$\theta = 0$ is stable (Lyapunov) if and only if $M^2 \sim R[\theta]$ or $M^2 \sim P_-$ in $Sp(\mathbb{R}^2)$.

In contrast to L_4, now linearized stability implies stability but there are cases where the linearized equation is unstable and the equilibrium is stable.

<u>Exercise 1.1</u> Explain why the local result is a consequence of the non-local result.

1.2. A quadratic Newton's equation

Consider the equation

$$\ddot{x} + x^2 = p(t), \qquad \int_0^T p(t)\,dt \leq p_0$$

where p is T-periodic. It was proved in [O2] that if

$$T^3 p_0 < 64$$

then there are at most two T-periodic solutions. Assume now that $p(t)$ has been chosen so that there exist exactly two, then if

$$T^3 p_0 < 4$$

one of them is linearly stable. The number 4 is sharp. Moreover, there exists a number σ_*, $\frac{1}{4} < \sigma_* < \frac{64}{81}$, which can be computed such that if

$$T^3 p_0 < \sigma_*$$

then this solution is stable. The number σ_* was not optimal and it was later improved by Zhang, Chu, Li [ZCL] although the optimal value is not known.

In contrast to the previous results the periodic solution is not explicitly known, the existence is determined via degree theory or some other global technique. The dissadvantadge of this type of result is that it depends on very special properties of the nonlinearity x^2. It is my impression that more flexible results should not be valid for all p's but for almost all.

1.3. The forced pendulum equation

Consider the equation

$$\ddot{x} + \beta \sin x = p(t)$$

where $\beta > 0$ and $p \in C(\mathbb{T})$ with $\int_0^{2\pi} p(t)\,dt = 0$.
It is well known that there exist at least two 2π-periodic solutions (variational of symplectic methods).

If

$$\beta \leq \frac{1}{4}$$

then, for almost all p's, at least one of them is stable (see [03]). Moreover the number $\frac{1}{4}$ is sharp. (see [04]). The techniques employed to prove this result are rather flexible. They have been already used by J. Chu, F. Wang in a preprint. My original intention was to prove this result in the course but later I realised that the proof is too long. Instead I have prepared a toy problem which is easier to prove but employs the same techniques.

For more references on non-local results I refer to papers by D. Nuñez, M. Zhang and his school, P. Torres and others.

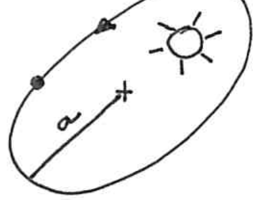
2. Definition of stability

Let $\phi_t(z)$ be the flow associated to the Hamiltonian system $(*)$. For each $z \in \Omega$ the solution $\phi_t(z)$ is defined on a maximal (open) interval I_z.

Let $z_* \in \Omega$ be a fixed point and assume that $\phi_t(z_*)$ is well defined for $t \geq 0$. This solution is called stable (in the Lyapunov sense) if given $\varepsilon > 0$ there exists $\delta > 0$ such that $\phi_t(z)$ is well defined for $t \geq 0$ if $|z - z^*| < \delta$ and $|\phi_t(z_*) - \phi_t(z)| < \varepsilon$.

This is the notion of stability for the future. If we replace $t \geq 0$ by $t \in \mathbb{R}$ then we obtain the notion of perpetual stability.

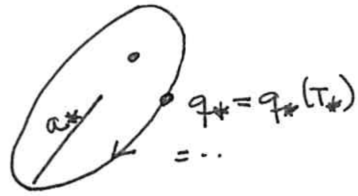
For periodic solutions this notion is too restrictive. For instance, the motion of a planet around the sun is unstable



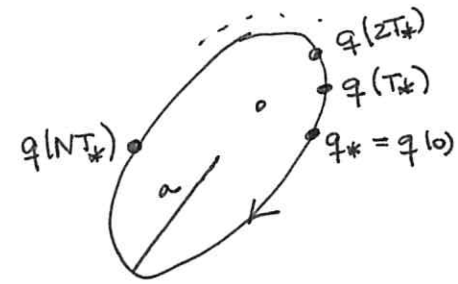
This is a problem in our framework with $\Omega = (\mathbb{R}^2 \setminus \{0\}) \times \mathbb{R}^2$ and $H(q,p) = \frac{1}{2}|p|^2 - \frac{1}{|q|}$. The reason for the instability is third Kepler law: the minimal period of an elliptic orbit is $T = 2\pi a^{3/2}$ where $a = \frac{1}{2}$ major axis. If we select an initial condition $z_* = (q_*, p_*)$ with $H(q_*, p_*) < 0$ and $q_* \wedge p_* \neq 0$ then $\phi_t(z_*)$ is periodic. The same will be true for a small perturbation z, if the major axis of the first orbit is $2a_*$, the major axis of the second, $2a$, will be close but in general it will be different.

Then the periods T_* and T will be close but different. Let us think of the positions of the two orbits at times $T_*, 2T_*, 3T_* \dots$ if $a_* < a$

$$q_* = q_*(T_*) = q_*(2T_*) = \dots = q_*(NT_*)$$



Every year (period T_*) the perturbed planet will not close the orbit and after many years $q_*(NT_*)$ and $q(NT_*)$ can be far away



The following exercise makes this idea more precise.

Exercise Assume that $F : \Omega \subset \mathbb{R}^d \to \mathbb{R}^d$ is smooth and let $\varphi_n(t)$ and $\varphi(t)$ be periodic solutions of $\dot{z} = F(z)$ with minimal periods T_n and T. In addition,

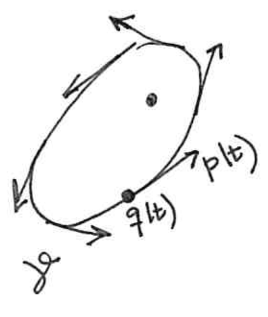
$$\frac{T_n}{T} \notin \mathbb{Q}$$

$\varphi(t)$ is not constant

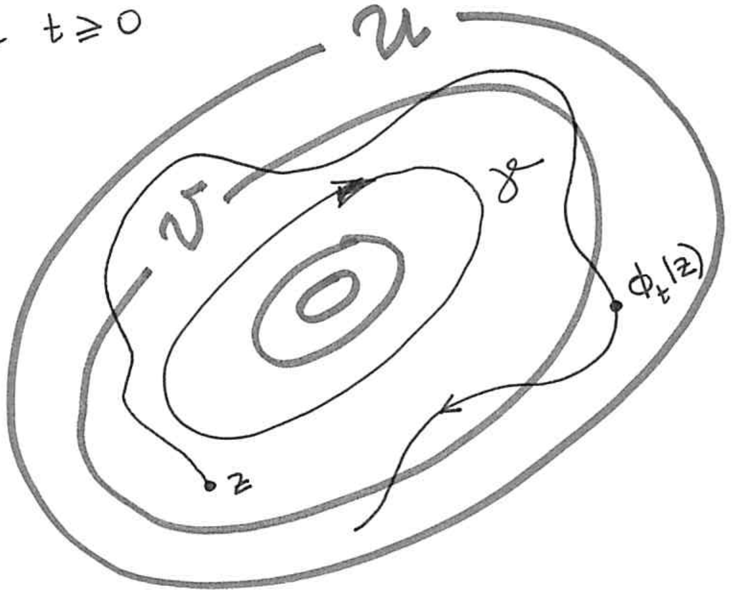
$\varphi_n(0) \to \varphi(0)$.

Then $\varphi(t)$ is not stable (in the Lyapunov sense).

If we go back to the elliptic orbits of Kepler problem we observe that a small perturbation will change slightly the geometry of the ellipse, hence the orbit $\gamma = \{(q(t), p(t)) : t \in \mathbb{R}\}$ will change slightly



We are lead to the following definition: a closed orbit $\gamma \subset \Omega$ is called <u>orbitally stable</u> if given a nghd $\mathcal{U} = \mathcal{U}(\gamma)$ there exists another nghd $\mathcal{V} = \mathcal{V}(\gamma)$ such that if $z \in \mathcal{V}$ then $\phi_t(z) \in \mathcal{U}$ for each $t \geq 0$



If γ is a closed orbit (not an equilibrium), $\nabla H(z) \neq 0$ for each $z \in \gamma$ and so the energy level $\{H = c\}$ where $c = H|_\gamma$ is a 3d manifold, at least in a nghd $\mathcal{U}$ of γ. We can restrict the flow $\phi_t(z)$ to this submanifold and consider the orbital stability only with respect to orbits lying on the same energy level, this leads to the weaker notion of <u>isoenergetic orbital stability</u>. In most cases both notions coincide but there are exceptional cases (see the Appendix).

Next we are going to introduce an important tool for the study of orbital stability: <u>transversal sections</u>.

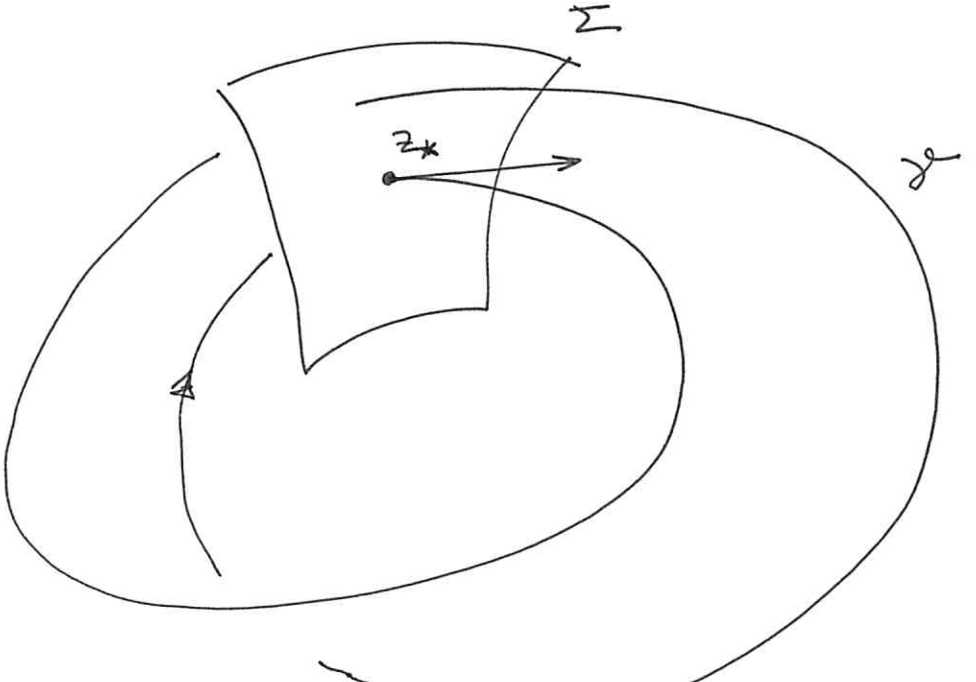
In the closed orbit γ we fix a point $z_* \in \gamma$. We know that $\nabla H(z_*) \neq 0$ and we assume, for instance,

$$\frac{\partial H}{\partial q_2}(z_*) \neq 0.$$

Then there exists a nghd $\mathcal{U}$ of z_* in $\mathbb{R}^4$ such that

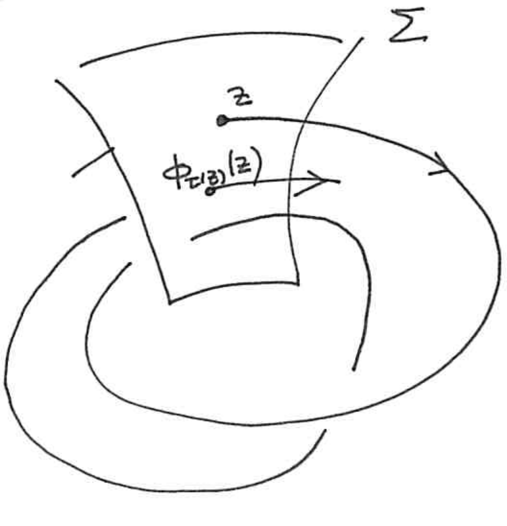
$$\Sigma = \{(q,p) \in \Omega \,/\, H(q,p) = c,\ p_2 = p_2^*\} \cap \mathcal{U}$$

is a surface contained in the energy level. Moreover the flow is transversal to Σ at z_* $\left(\dot{p}_2 = -\frac{\partial H}{\partial q_2} \right)$



In a neighd $\Sigma_1 \subset \Sigma$ of z_* we can find a return: for each $z \in \Sigma_1$ there exists $\tau = \tau(z) > 0$ such that $\Phi_{\tau(z)}(z) \in \Sigma$. Moreover τ is a smooth function with $\tau(z_*) = T_* > 0$ period.

Exercise: Justify this via the implicit function theorem



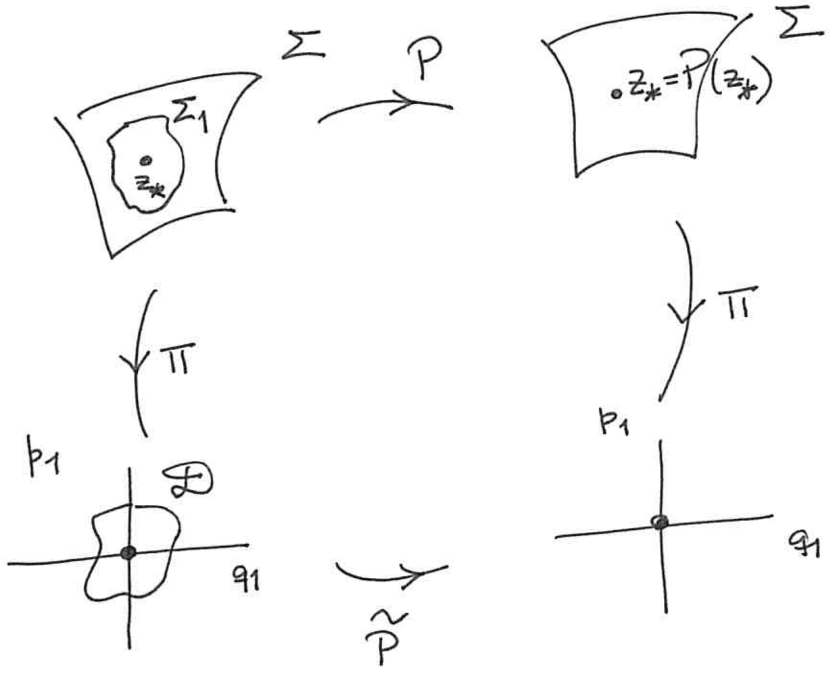
We define the Poincaré map $P : \Sigma_1 \to \Sigma$, $P(z) = \phi_{\tau(z)}(z)$ and it turns out that P is symplectic; that is

$$\omega\left((dP)_z \xi, (dP)_z \eta \right) = \omega(\xi, \eta) \quad \text{if } z \in \Sigma_1, \ \xi, \eta \in T_z(\Sigma)$$

$\omega|_{T_z(\Sigma)}$ non-degenerate

$$\omega(\xi,\eta) = \langle \xi, J\eta \rangle, \ \xi,\eta \in \mathbb{R}^4, \ J = \begin{pmatrix} 0 & I_2 \\ -I_2 & 0 \end{pmatrix}$$

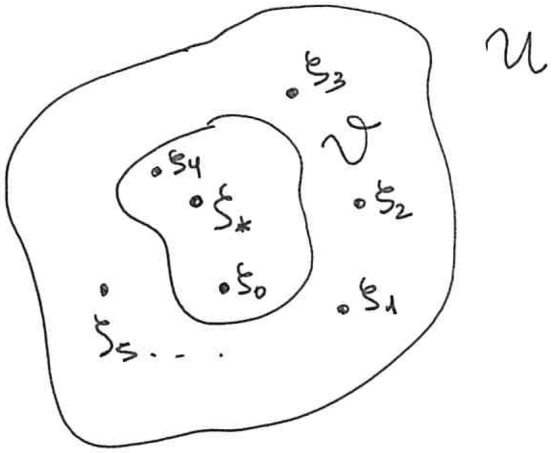
In the surface Σ we can express q_2 and p_2 as functions of q_1 and p_1, $p_2 = \text{constant} = p_2^*$ and $q_2 = \varphi(q_1, p_1)$ from $H(q_1, p_1, q_2, p_2^*) = c$. Then the projection $\pi(q,p) = (q_1, p_1)$ defines a diffeomorphism between Σ and $\mathbb{R}^2$. We can transport P to $\mathbb{R}^2$,



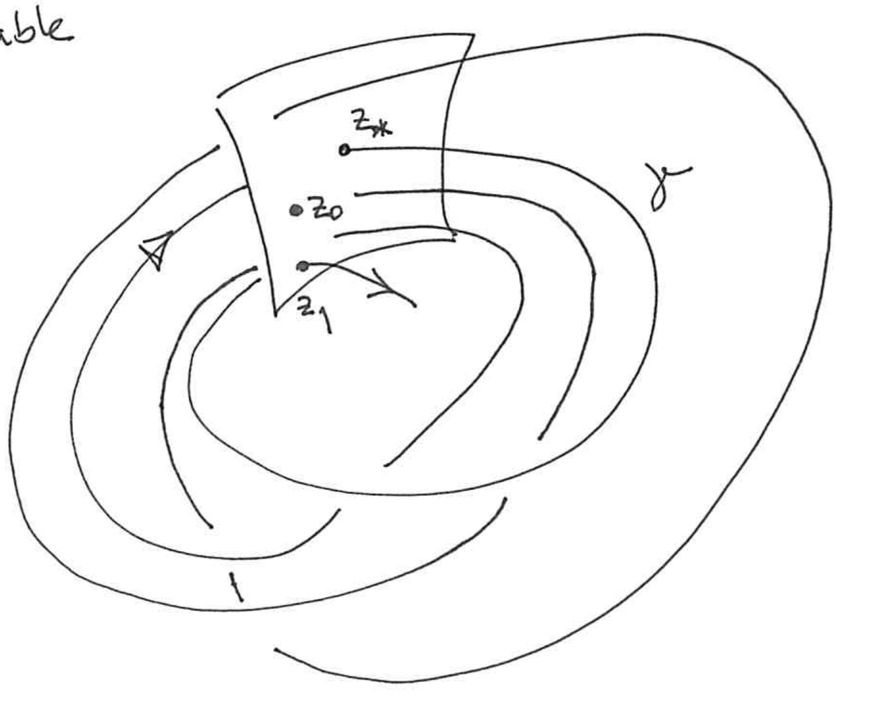
$\tilde{P} : \mathcal{D} \subset \mathbb{R}^2 \to \mathbb{R}^2$ is an area-preserving diffeomorphism from $\mathcal{D}$ onto $\mathcal{D}_1 = \tilde{P}(\mathcal{D})$ with a fixed point at $\pi(z_*)$. Note that

$$\pi^*(dq_1 \wedge dp_1) = \omega|_\Sigma$$

There is a natural notion of stability of fixed points for the discrete system $\xi_{n+1} = \tilde{P}(\xi_n)$. Given the fixed point $\xi_* = \Pi(z_*)$ we say that ξ_* is stable if for each nghd $\mathcal{U} = \mathcal{U}(\xi_*)$ there exists another nghd $\mathcal{V} = \mathcal{V}(\xi_*)$ such that the iterates $\tilde{P}^n(\mathcal{V})$ are well defined for each $n \geq 0$ and contained in $\mathcal{U}$



By continuous dependence (with some care) it is possible to ~~proof~~ prove that ξ_* is stable for $\tilde{P}$ if and only if γ is isoenergetically orbitally stable



In the special case of time periodic systems of one degree of freedom this is just stability in the Lyapunov sense for the original system.

For more details we refer to [MZ] and [MHO]. See also www.ugr.es/~rortega/PDFs/Talca.pdf

Appendix : A closed orbit orbitally unstable but isoenergetically orbitally stable

We work with symplectic polar coordinates

$$q_1 + i p_1 = \sqrt{2 r_1}\, e^{i\theta_1}, \quad q_2 + i p_2 = \sqrt{2 r_2}\, e^{i\theta_2}$$

and consider the Hamiltonian function

$$H(r_1, r_2) = (r_1 - r_2)\left(1 + (r_1 - r_2)^2 r_1^2\right), \quad \Omega = (\mathbb{R}^2 \setminus \{0\}) \times (\mathbb{R}^2 \setminus \{0\})$$

Let us concentrate on the energy level $H = 0$, this is equivalent to $r_1 - r_2 = 0$. We compute the derivatives of H,

$$\left.\begin{aligned} \frac{\partial H}{\partial r_1} &= 1 + (r_1 - r_2)^2 \left[5 r_1^2 - 2 r_1 r_2\right] \\ \frac{\partial H}{\partial r_2} &= -1 - 3(r_1 - r_2)^2 r_1^2 \end{aligned}\right\}$$

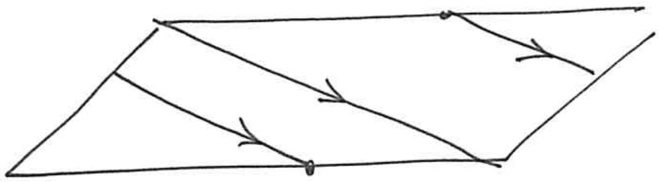
and observe that $\frac{\partial H}{\partial r_1} = 1$, $\frac{\partial H}{\partial r_2} = -1$ on $H = 0$. This implies that on the level $H=0$ all orbits are 2π-periodic

$$\dot{r}_i = 0, \quad \dot{\theta}_i = -\frac{\partial H}{\partial r_i} \qquad \left\{\begin{aligned} & r_1(t) = \rho_0 = r_2(t) \\ & \theta_1(t) = -t + \theta_{10}, \quad \theta_2(t) = t + \theta_{20} \end{aligned}\right.$$

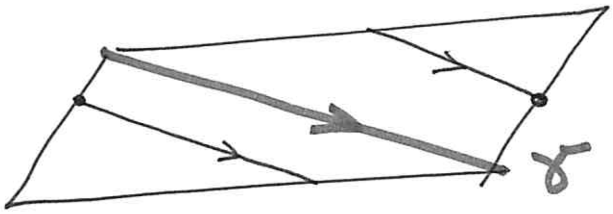
We select γ: $r_1 = r_2 = 1$, $\theta_1 = -\theta_2$ and observe that this closed orbit is isoenergetically stable

$H=0 \Longleftrightarrow r_1=r_2=\rho$

$\rho = 1+\delta$



$\rho = 1$

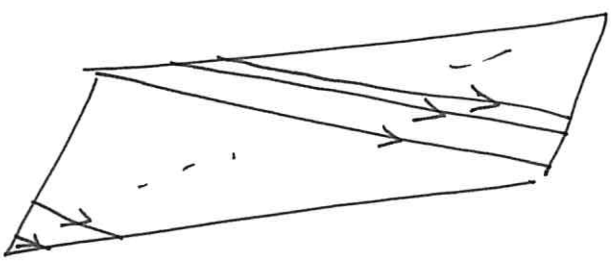


Let us prove that γ is orbitally unstable when we include other energy levels. We take $r_1 = 1+\varepsilon$, $r_2 = 1-\varepsilon$, $\theta_{10} = \theta_{20} = 0$

then

$$\left.\begin{aligned} \dot\theta_1 &= -\frac{\partial H}{\partial r_1} = -1-4\varepsilon^2(1+\varepsilon)(3+7\varepsilon) \\ \dot\theta_2 &= -\frac{\partial H}{\partial r_2} = 1+12\varepsilon^2(1+\varepsilon)^2 \end{aligned}\right\}$$

Now we select ε so that the quotient of the two frequencies is irrational, say $\varepsilon_n = \frac{\sqrt{2}}{n}$. Then the orbit γ_n is dense on the torus $r_1 = 1+\varepsilon_n$, $r_2 = 1-\varepsilon_n$



and so the points of γ_n accumulate on the whole torus $r_1 = r_2 = 1$ which contains strictly the orbit γ

3. Stable fixed points of area-preserving maps

3.1. We first recall the notion of stable fixed point. Let $\mathcal{D}$ and $\mathcal{D}_1$ be open subsets of $\mathbb{R}^2$ and

$$h : \mathcal{D} \to \mathcal{D}_1, \quad z_1 = h(z)$$

a homeomorphism having a fixed point $z_* \in \mathcal{D}$, $h(z_*) = z_*$. We say that z_* is stable (in the future) if given any nghd $\mathcal{U} = \mathcal{U}(z_*)$ there exists another nghd $\mathcal{V} = \mathcal{V}(z_*)$ such that for each integer $n \geq 0$ the iterate $h^n(\mathcal{V})$ is well defined and

$$h^n(\mathcal{V}) \subseteq \mathcal{U}.$$

The notion of perpetual stability is obtained after replacing $n \geq 0$ by $n \in \mathbb{Z}$.

Exercise 3.1 Discuss the stability properties of $z_* = 0$ if $h(z) = \lambda z$ $(\lambda > 0)$ or $h(z) = R[\theta]z$, $R[\theta] = \begin{pmatrix} \cos\theta & -\sin\theta \\ \sin\theta & \cos\theta \end{pmatrix}$.

A rather obvious property of the notion of stability is that it is invariant under changes of variable. By a change of variable we understand a homeomorphism $\psi : \Delta \to \Delta_1$ between two open sets in $\mathbb{R}^2$ with $\psi(z_*) = w_*$. Then $\hat{h} = \psi \circ h \circ \psi^{-1}$ is well defined on some nghd of w_* and w_* is stable under $\hat{h}$ if and only if z_* is stable under h.

Next we present a characterization of stability in terms of invariant nghds.

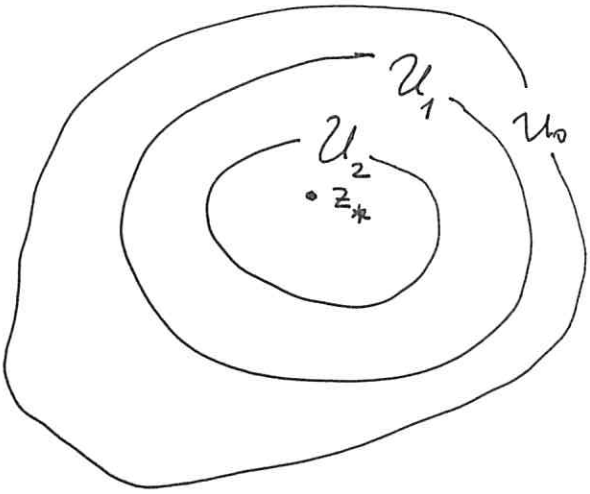
Proposition 3.1 The following statements are equivalent:

(i) z_* is stable in the future [resp. perpetually]

(ii) There exist a sequence $\{\mathcal{U}_n\}$ of open and bounded sets satisfying

$$\overline{\mathcal{U}_{n+1}} \subset \mathcal{U}_n, \ \overline{\mathcal{U}_n} \subset \mathcal{D}, \ \bigcap_n \overline{\mathcal{U}_n} = \{z_*\} \quad \text{and}$$

$$h(\mathcal{U}_n) \subset \mathcal{U}_n \ [\text{resp. } h(\mathcal{U}_n) = \mathcal{U}_n]$$



Proof. (ii) $\Rightarrow$ (i) The compacts sets $\overline{\mathcal{U}_n}$ converge to $\{p\}$ in the Hausdorff topology. Given $\mathcal{U}$ we can find n large enough so that $\overline{\mathcal{U}_n} \subset \mathcal{U}$. Then we select $\mathcal{V} = \overline{\mathcal{U}_n}$.

(i) $\Rightarrow$ (ii) Fix a disk D_0 centered at z_* and such that $\overline{D_0} \subset \mathcal{D}$. Then we find $\mathcal{V}_0$ such that $h^n(\mathcal{V}_0) \subset D_0$ for each $n \geq 0$. Then

$$\mathcal{U}_0 = \bigcup_{n\geq 0} h^n(\mathcal{V}_0)$$ is open, contains z_* and satisfies

$\mathcal{U}_0 \subset D_0$ and $h(\mathcal{U}_0) \subset \mathcal{U}_0$. We construct $\mathcal{U}_n$ by induction with $D_n \to \{z_*\}$, $\overline{D_{n+1}} \subset \mathcal{U}_n$.

3.2. Area preserving maps The map $h : \mathcal{D} \to \mathcal{D}_1$ is area preserving if

$$\mu(h(B)) = \mu(B)$$

for each Borel set $B \subset \mathcal{D}$. Here μ is the Lebesgue measure in the plane (*).

Simple examples are linear maps $h(z) = Az$ with $A \in \mathbb{R}^{2\times 2}$, $|\det A| = 1$.

Exercise 3.2 Prove that the non-linear map $h(z) = R[\theta + \beta|z|^2]z$

(*) A more restrictive notion appears when Borel sets are replaced by Lebesgue measurable sets (see [OU]).

with $\beta \neq 0$ is an area-preserving map. Describe the dynamics.

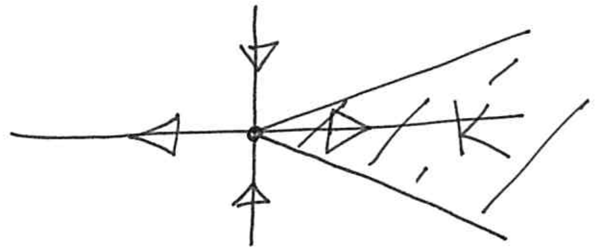
Let $X : \mathbb{R} \times \mathbb{R}^2 \to \mathbb{R}^2$, $X = X(t,x)$ be a $C^{0,1}$ vector field with

$$\operatorname{div}_x X = 0.$$

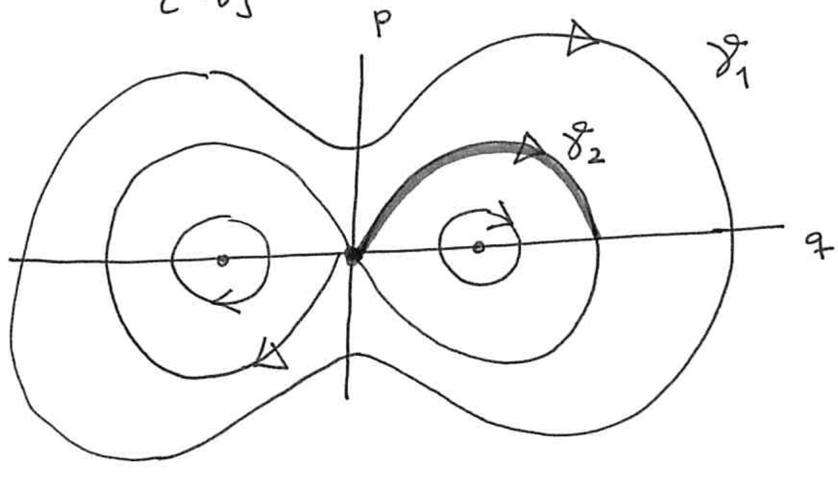
Let $x(t;x_0)$ be the solution of $\dot{x} = X(t,x)$, $x(0) = x_0$. For fixed $t \in \mathbb{R}$, the map $h(x_0) = x(t;x_0)$ is an area-preserving homeomorphism between appropriate domains. This is a consequence of Liouville theorem. In particular this is the case for Hamiltonian systems $X = J \nabla_x H$.

Area-preserving maps can have positively invariant open sets that are not invariant. We present two examples:

i) $h(z) = \begin{pmatrix} 2 & 0 \\ 0 & \frac{1}{2} \end{pmatrix} z$, $\quad h(K) \subsetneq K$



ii) Let $\{\phi_t\}$ be the Hamiltonian flow with phase portrait



Let Ω be the region in the interior of γ_1 excepting $\{\gamma_2 \cap \{p \geq 0\}\}$ and the origin. Then, for each $t > 0$

$\phi_t(\Omega) \subsetneqq \Omega$ because $\phi_t(\Omega)$ contains a smaller piece of γ_2.

The next result shows that in many cases positive invariance implies invariance.

<u>Lemma 3.2</u> Assume that Ω is an open set of bounded measure with $\overline{\Omega} \subset \mathcal{D}$ and $\operatorname{int}(\overline{\Omega}) = \Omega$. If $h(\Omega) \subseteq \Omega$ then $h(\Omega) = \Omega$

<u>Proof</u>. If $h(\Omega) \subseteq \Omega$ we claim that $\Omega \subset h(\overline{\Omega})$ for otherwise $\Omega \setminus h(\overline{\Omega})$ should be a non-empty open subset of Ω, hence a set of positive measure. But

$$\infty > \mu(\Omega) \geq \underbrace{\mu(\Omega \setminus h(\overline{\Omega}))}_{>0} + \underbrace{\mu(h(\Omega))}_{\mu(\Omega)}, \quad \text{contradiction}.$$

Once we know that $\Omega \subset h(\overline{\Omega})$ the rest of the argument is purely topological. ~~From~~ $\cancel{\overline{\Omega} \subset \overline{h(\Omega)} = h(\overline{\Omega})}$, Indeed,

$$\Omega \subset \operatorname{int}(h(\overline{\Omega})) = h(\operatorname{int}(\overline{\Omega})) = h(\Omega).$$

<u>Exercise 3.3</u> Let Ω be an open subset of $\mathbb{R}^2$ and $\omega = \operatorname{int}(\overline{\Omega})$. Then $\Omega \subset \omega \subset \overline{\Omega}$ and $\operatorname{int}(\overline{\omega}) = \omega$.

<u>Proposition 3.3</u> For area-preserving maps, stability in the future and perpetual stability are equivalent notions

<u>Proof</u> If z_* is stable in the future then by Prop 3.1 we can find nghds $\{U_n\}$ in the conditions prescribed by this result. In particular, $h(U_n) \subset U_n$. Define $\mathcal{V}_n = \operatorname{int}(\overline{U_n})$, then $U_n \subset \mathcal{V}_n \subset \overline{U_n}$ and $h(\mathcal{V}_n) = \mathcal{V}_n$. This is a consequence of the previous exercise and Lemma 3.2. Again Prop 3.1 implies that z_* is perpetually stable.

3.3 Lyapunov functions and first integrals

Let $V : \mathcal{D} \to \mathbb{R}$ be a continuous function satisfying

$$V(z) > 0 \text{ if } z \in \mathcal{D} \setminus \{z_*\}, \quad V(z_*) = 0.$$

We say that V is a Lyapunov function if

$$V(h(z)) \leq V(z) \quad \text{for each } z \in \mathcal{D} \text{ with } h(z) \in \mathcal{D}.$$

Exercise 3.4 Prove that the existence of a Lyapunov function implies the stability of z_*.

We prove that every Lyapunov function is (locally) a first integral.

Proposition 3.4 Assume that there exists a Lyapunov function V. Then there exists a nghd $\mathcal{U}$ of z_* such that $h(\mathcal{U}) = \mathcal{U}$ and $V(h(z)) = V(z)$ if $z \in \mathcal{U}$.

Proof. We know that z_* is stable and so there is a bounded and open invariant set $\mathcal{U}$ with $z_* \in \mathcal{U}$, $\overline{\mathcal{U}} \subset h^{-1}(\mathcal{D})$. Since h is area-preserving and $h(\mathcal{U}) = \mathcal{U}$ we deduce that

$$\int_{\mathcal{U}} V(x)\,dx = \int_{\mathcal{U}} V(h(x))\,dx.$$

Note that $\int_{\mathcal{U}} V = \int_0^\infty F_V(t)\,dt$ and $\int_{\mathcal{U}} V \circ h = \int_0^\infty F_{V\circ h}(t)\,dt$

with $F_V(t) = \mu(\{x \in \mathcal{U} : V(x) > t\}) = \mu(\{x \in \mathcal{U} : V(h(x)) > t\})$
$= F_{V \circ h}(t)$

From $V - V\circ h \geq 0$ on $\mathcal{U}$ and $\int_{\mathcal{U}} (V - V\circ h) = 0$ we deduce that $V = V \circ h$ almost everywhere, but we are dealing with continuous functions and so it holds everywhere.

3.4. Invariant "curves" and stability

Up to now all discussions could be adapted to measure-preservi maps in $\mathbb{R}^d$ with $d > 2$. The contents of this section are specific of two dimensions. First we recall some facts of the topology of the plane, given a domain (open + connected) $\Omega \subset \mathbb{R}^2$, we denote by $\hat{\Omega}$ the smallest simply connected domain containing Ω, that is

i) $\Omega \subset \hat{\Omega}$, $\hat{\Omega}$ simply connected domain

ii) if $\Omega \subset \omega$, ω simply connected domain $\Rightarrow \hat{\Omega} \subset \omega$

Intuitively we can say that $\hat{\Omega}$ is obtained by filling in the holes of Ω. Note that $\hat{\Omega} \cong \mathbb{R}^2$ (this is a consequence of Riemann's th on conformal mappings).

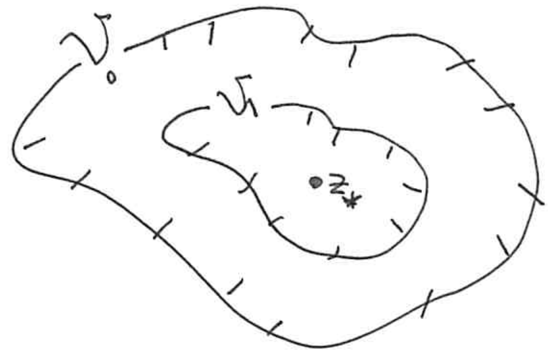
<u>Exercise 3.5</u> Prove that $\hat{\Omega}$ always exists. Given Ω with $\overline{\Omega} \subset \mathcal{D}$ prove that $h(\hat{\Omega}) = \widehat{h(\Omega)}$.

Assume that z_* is stable and let $\mathcal{U}_n$ be a sequence of bounded and open sets with

$\overline{\mathcal{U}_{n+1}} \subset \mathcal{U}_n$, $\overline{\mathcal{U}_0} \subset \mathcal{D}$, $\bigcap_n \mathcal{U}_n = \{z_*\}$, $h(\mathcal{U}_n) = \mathcal{U}_n$.

We can assume that $\mathcal{U}_n$ is connected since otherwise we would take the connected component of z_*. Next we fill in the holes of $\mathcal{U}_n$, $\mathcal{V}_n = \widehat{\mathcal{U}_n}$. We observe that $\mathcal{V}_n$ is also invariant under h. Moreover $\overline{\mathcal{V}_n} \to \{z_*\}$ in the Hausdorff sense (Take a sequence of disks centered at z_* with $\mathcal{U}_n \subset D_n$ and $D_n \to \{z_*\}$.

The sets $\mathcal{V}_n$ are homeomorphic to open disks but the boundaries can be very strange



In any case $h(\partial V_n) = \partial V_n$. In some books of topology of the plane the boundary of a simply connected domain is called a "curve". With this terminology we have proved the following result: a fixed point is stable if and only if it is surrounded by invariant "curves".

Handel constructed in [H] an example where all invariant "curves" were non locally connected continua (pseudo-circles).

4. Linearization around fixed points

4.1. The symplectic group

We recall that $Sp(\mathbb{R}^2)$ is composed by the matrices $A \in \mathbb{R}^{2\times 2}$ satisfying $\det A = 1$.

They represent linear maps preserving area and orientation.

The Lie group $Sp(\mathbb{R}^2)$ has a well known topological desciption

$$Sp(\mathbb{R}^2) \cong \text{open solid torus.}$$

To understand this homeomorphism it is convenient to represent the group in complex notation. The linear map induced by A can be written as

$$L_A : \mathbb{C} \to \mathbb{C}, \quad L_A : z \mapsto az + b\bar{z} \quad \text{with } a, b \in \mathbb{C} \text{ given by}$$

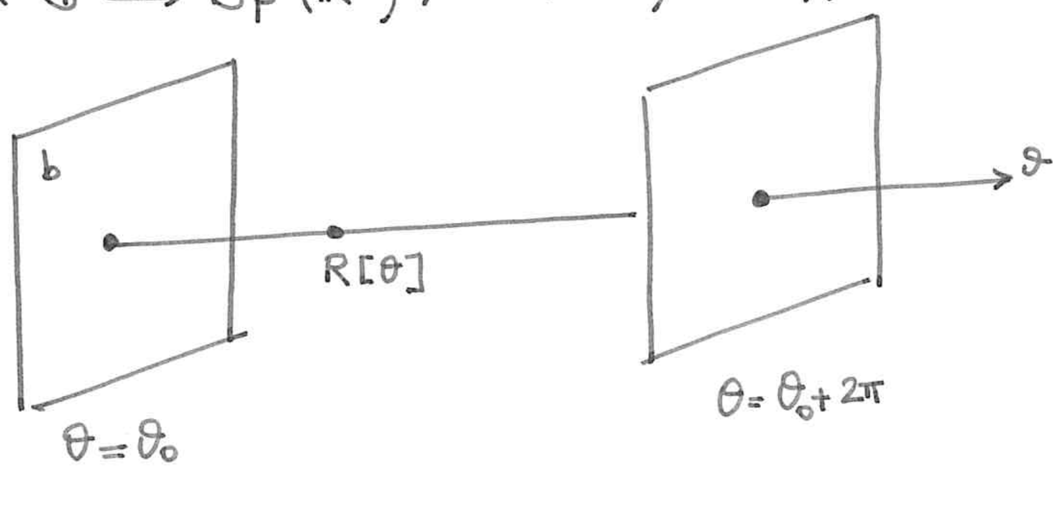
$$a = \alpha + i\beta, \quad b = \gamma + i\delta, \qquad A = \begin{pmatrix} \alpha+\gamma & \delta-\beta \\ \delta+\beta & \alpha-\gamma \end{pmatrix}.$$

Then $\det A = 1$ is equivalent to

$$|a|^2 - |b|^2 = 1.$$

We construct the homeomorphism

$$\mathbb{C} \times \mathbb{S}^1 \longrightarrow Sp(\mathbb{R}^2), \quad (b, e^{i\theta}) \mapsto L_A \quad \text{where } a = \sqrt{1+|b|^2}\, e^{i\theta}$$

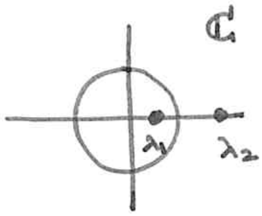


The θ-axis $(b=0)$ is the circumference of rotations.

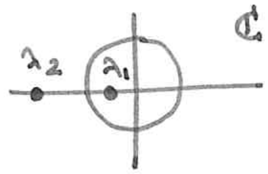
To understand the stability of the origin $z_*=0$ with respect to L_A we employ the trace of A,

$$\Delta := \operatorname{tr} A = 2\,\mathrm{Re}\, a = 2\sqrt{1+|b|^2}\cos\theta .$$

If $|\Delta|>2$ the eigenvalues are real $|\lambda_1|<1<|\lambda_2|$

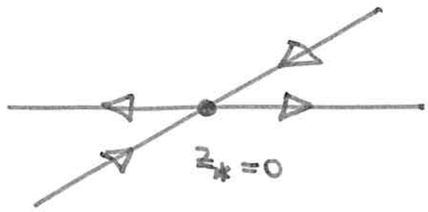


$(\Delta>2)$



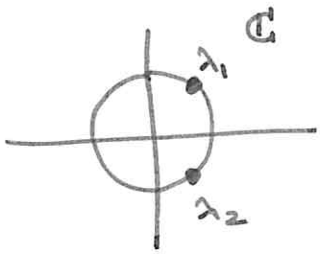
$(\Delta<-2)$

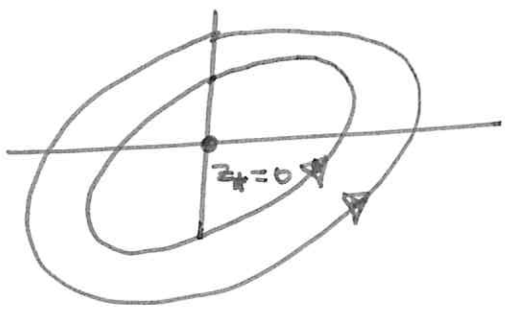
The matrix A is conjugate in $Gl(\mathbb{R}^2)$ to $\begin{pmatrix}\lambda_1 & \\ & \lambda_2\end{pmatrix}$ and so the origin is unstable



$z_*=0$ is hyperbolic $(|\Delta|>2)$

If $|\Delta|<2$ the eigenvalues are complex and conjugate $\lambda_1=\overline{\lambda_2}=e^{i\theta}$, $\theta\in\,]0,\pi[\,\cup\,]\pi,2\pi[$, and A is conjugate in $Gl(\mathbb{R}^2)$ to $R[\theta]$, the origin is stable

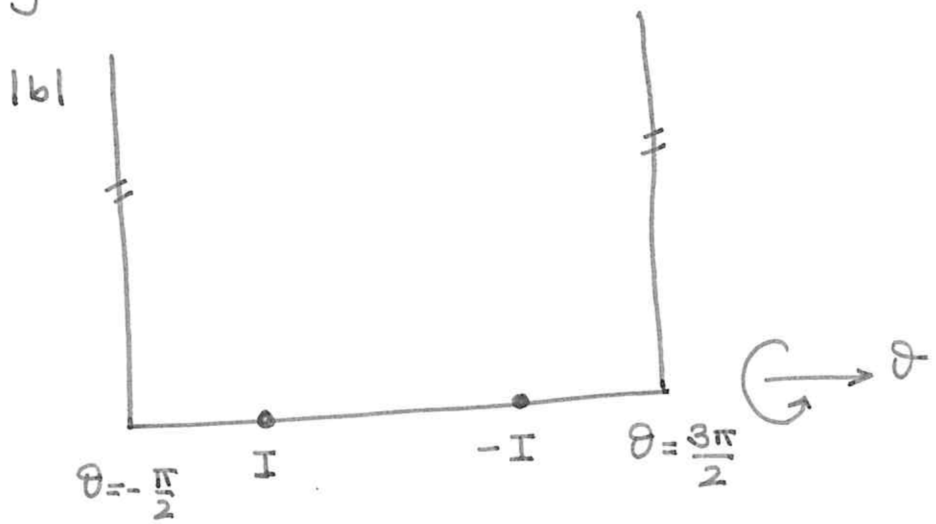




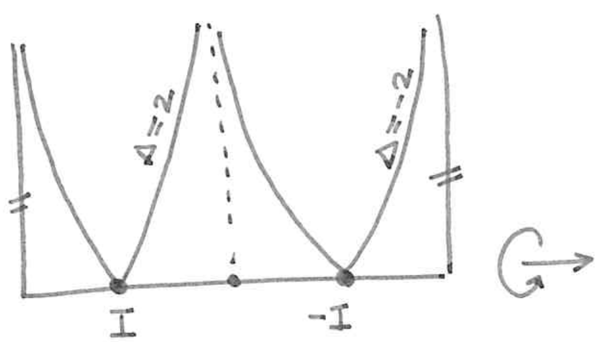
$z_*=0$ is elliptic $(|\Delta|<2)$

Finally, if $|\Delta| = 2$ there is a double eigenvalue $\lambda_1 = \lambda_2 = 1$ or $\lambda_1 = \lambda_2 = -1$, then either $A = \pm I$ (parabolic stable) or A is conjugate to $\begin{pmatrix} \pm 1 & 1 \\ 0 & \pm 1 \end{pmatrix}$ in $Gl(\mathbb{R}^2)$ (parabolic unstable).

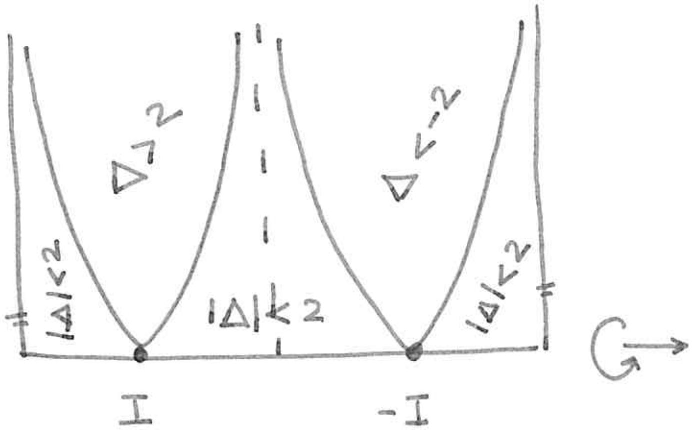
Let us now describe this dynamical classification in a topological way. We visualize $\tilde{Sp}(\mathbb{R}^2)$ as an infinite rectangle with coordinates $|b| \geq 0$ and $\theta \in [\theta_0, \theta_0 + 2\pi]$ that is rotating around the θ-axis and such that θ_0 and $\theta_0 + 2\pi$ are identified. For convenience we choose $\theta_0 = -\frac{\pi}{2}$



We draw the parabolic set $\Delta = \pm 2$, $\sqrt{1 + |b|^2} = \dfrac{\pm 1}{\cos\theta}$



Then $\tilde{Sp}(\mathbb{R}^2) \setminus \{\Delta = \pm 2\}$ has 4 components, two of them elliptic and two hyperbolic



Exercise 4.1 Describe the level sets $\Delta = \text{constant}$

Exercise 4.2 Describe the stability properties of $z_* = 0$ for linear maps with $\det A = -1$.

4.2 The first approximation

Let $h : \mathcal{D} \to \mathcal{D}_1$ be a C^1-diffeomorphism with

$$\det h'(z) = 1 \quad \text{if } z \in \mathcal{D}.$$

Then h is area-preserving and given a fixed point z_*, the differential at z_*

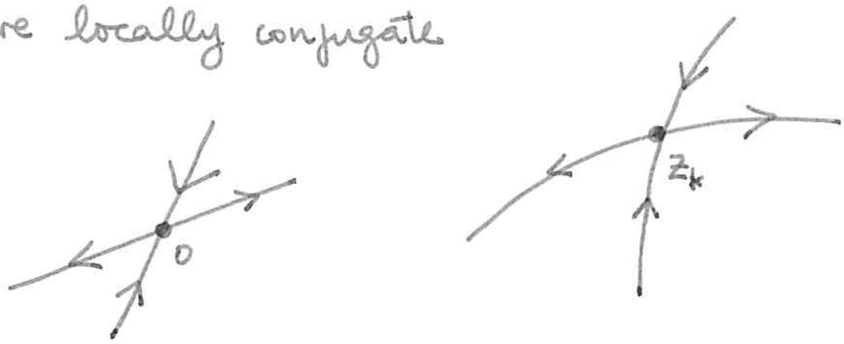
$$L = h'(z_*)$$

is in $Sp(\mathbb{R}^2)$.

It seems natural to compare the dynamics of $z_{n+1} = h(z_n)$ and $z_{n+1} = L z_n$ in small nghds of z_* and the origin.

We say that z_* is linearly stable if the origin is stable for L. This means that either L is elliptic or parabolic-stable $(L = \pm I)$.

We want to discuss possible connections between stability and linearized stability. When L is hyperbolic, Hartman-Grossman theorem says that the dynamics of h and L are locally conjugate



Hence, $\quad L$ hyperbolic $\Longrightarrow$ z_* unstable for h.

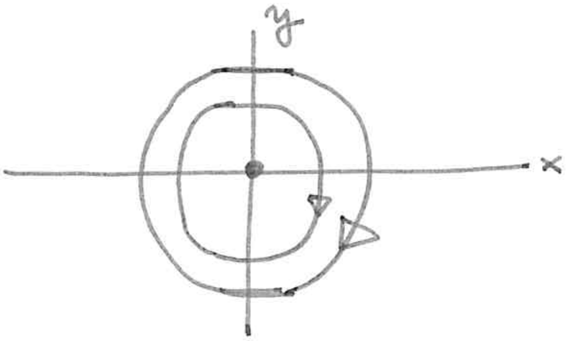
In general there are no further connections between stability and linearized stability. We illustrate it with two examples.

Example I $\quad$ z_* is stable but linearly unstable

Consider the Hamiltonian function

$$H(x,y) = \frac{1}{2} y^2 + \frac{1}{4} x^4 \quad , \qquad z = (x,y)$$

and the associated flow ϕ_t in $\mathbb{R}^2$. The phase portrait is



and the flow is globally defined. Let us fix $T \neq 0$ and consider $h = \phi_T$. Then h is an area-preserving analytic diffeomorphism. Moreover the origin $z_* = 0$

is stable because H is a Lyapunov function ($H \circ h = H$, $H > 0$ if $z \neq 0$, $H(0) = 0$). To compute

$$L = h'(0) = \left.\frac{\partial \phi_t}{\partial z}\right|_{t=T,\, z=0}$$

we differentiate with respect to initial conditions. For the Hamiltonian system $\dot{x} = y$, $\dot{y} = -x^3$, the linearized system around ~~x=y=0~~ a solution $(x(t), y(t))$ is

$$\dot{\xi} = \eta, \quad \dot{\eta} = -3x(t)^2 \xi .$$

For $x = y = 0$ we obtain $\dot{\xi} = \eta$, $\dot{\eta} = 0$. Then

$$L = \begin{pmatrix} 1 & T \\ 0 & 1 \end{pmatrix}$$ because $\frac{\partial \phi_t}{\partial z}(0)$ is the matrix solution $\begin{pmatrix} 1 & t \\ 0 & 1 \end{pmatrix}$.

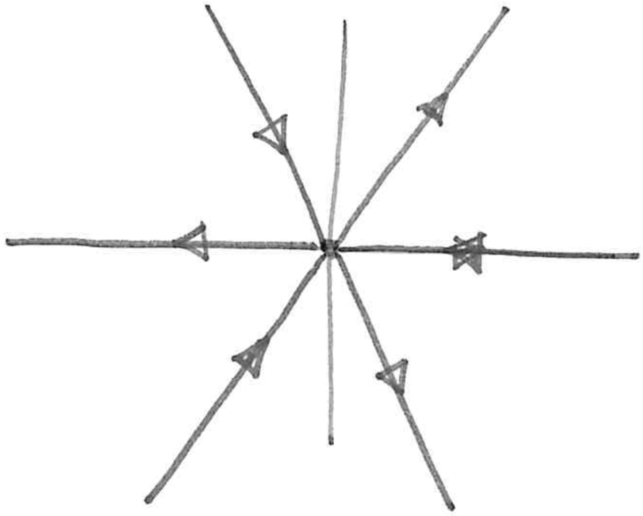
<u>Example II</u> <u>z_* is linearly stable but unstable</u>

We fix an integer $N \geq 3$ and consider the real analytic Hamiltonian function

$$H(z, \bar{z}) = \operatorname{Im}(z^N).$$

The phase ~~pha~~ portrait of the associated flow is a generalized saddle having stable / unstable manifold with N branches.

The next drawing is for $N = 3$.



This can be checked via the symplectic change of variable $z = \sqrt{2r}\, e^{i\vartheta}$ leading to the ~~H~~ new Hamiltonian function

$\mathcal{H}(\vartheta, r) = (2r)^{N/2} \sin N\vartheta.$

Let ϕ_t be the Hamiltonian flow associated to H and consider $h_1 = \phi_T$. This map is well defined in a nghd of the origin and satisfies $h_1(0)=0$, $h_1'(0) = I$ because the linearized system around the origin is

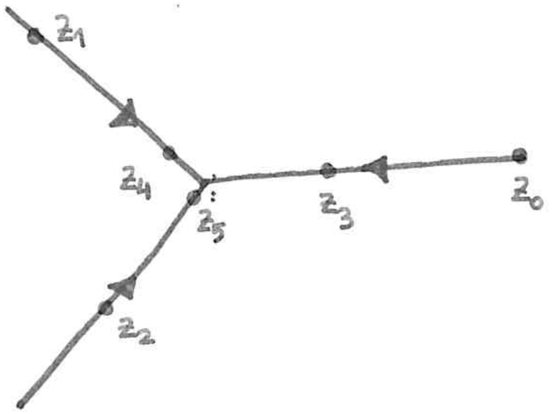
$$\dot{\xi} = 0, \quad \dot{\eta} = 0.$$

Note that $H = o(|z|^2)$.

Next we consider a rotation of angle $\frac{2k\pi}{N}$ and define

$$h = R\left[\frac{2k\pi}{N}\right] \circ h_1$$

From the above computations we know that $h(0)=0$ and $L = h'(0) = R\left[\frac{2k\pi}{N}\right]$. Moreover $z_* = 0$ is unstable because the stable and unstable manifolds for h_1 are also invariant under h,

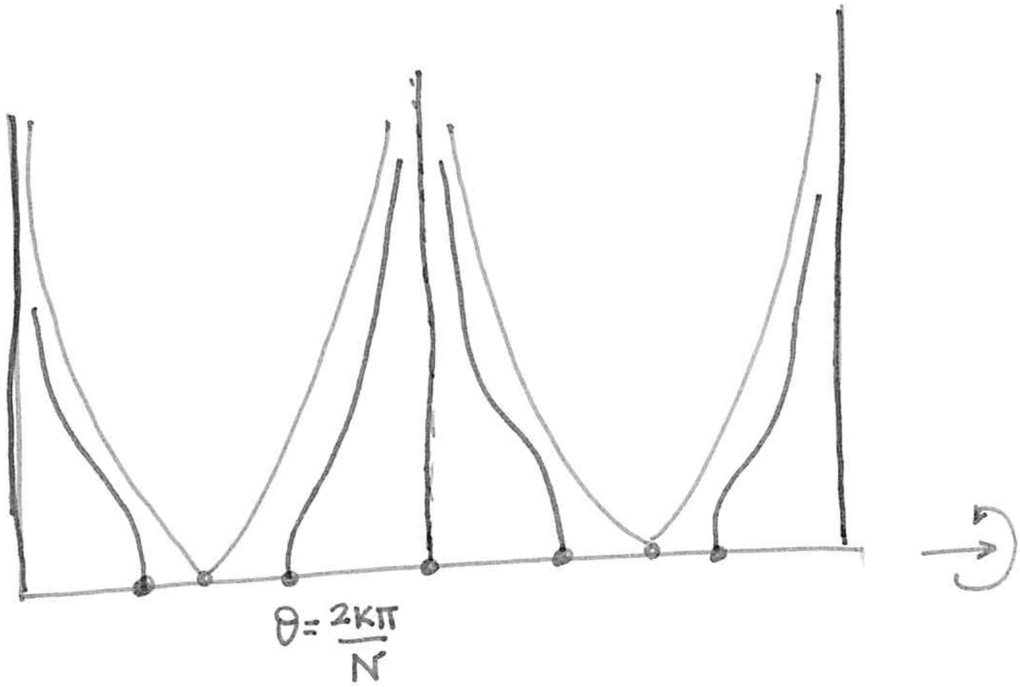


Dynamics under h

$z_n \to 0$ as $n \to +\infty$

Exercise 4.3 Prove that there exists a subset $\mathcal{D} \subset Sp(\mathbb{R}^2)$ which is dense and such that for each $A \in \mathcal{D}$ there exists an analytic area preserving map h satisfying $h(0)=0$, $h'(0)=A$, $z_* = 0$ is unstable.

Hint:



5. Nonlinear approximations

To simplify the exposition we shall work with a real analytic map $h : \mathcal{U} \subset \mathbb{R}^2 \to \mathbb{R}^2$

satisfying $h(0) = 0$ and $\det h'(z) = 1$ if $z \in \mathcal{U}$.

Here $\mathcal{U}$ is an open set containing the origin. We observe that the inverse function theorem implies that h is an area preserving diffeomorphism between two small nghds of the origin.

5.1 Birkhoff Normal Form

Assume that $h'(0) \sim R[\theta]$ in $Sp(\mathbb{R}^2)$

with $\theta \neq \frac{2k\pi}{n}$, $n = 1, 2, 3, 4$.

Then there exists a real analytic area-preserving diffeomorphism ψ (defined on a nghd of the origin) and a number $\beta_1 \in \mathbb{R}$ such that

$$\psi^{-1} \circ h \circ \psi(z) = R[\theta + \beta_1 |z|^2] z + O(|z|^4)$$

as $z \to 0$.

This result more or less says that if the linear part is elliptic then the third order approximation is a twist map. The proof is purely algebraic and can be found in [SM]. See also

www.ugr.es/~rortega/PDFs/buenosaires4

The change of variables Ψ is highly non-unique but the number β_1 is independent of the chosen Ψ. In this sense we can say that β_1 is a simplectic invariant.

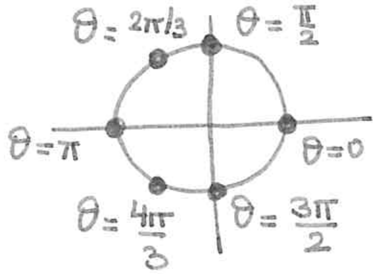
When $h'(0) = R[\theta]$ the number β_1 can be computed by the following formula

$$(*) \qquad \beta_1 = \operatorname{Im}\left(e^{-i\theta} N\right) - \frac{3\sin\theta}{1-\cos\theta}|A|^2 - \frac{\sin 3\theta}{1-\cos 3\theta}|G|^2$$

where we are using complex notation a h has the expansion

$$e^{i\theta} z + Az^2 + Bz\bar{z} + G\bar{z}^2 + Mz^3 + Nz^2\bar{z} + Pz\bar{z}^2 + Q\bar{z}^3.$$

The excluded angles are called strong resonances



It is possible to obtain normal forms of higher order if some more angle are excluded. In particular if we assume that the angle is not commensurable with 2π,

$$\theta \neq \frac{2k\pi}{n}, \quad n = 1, 2, \dots N, \dots$$

then for each $N \geq 1$ there exists Ψ_N as before and numbers $\beta_1, \dots \beta_N$ such that

$$\Psi_N^{-1} \circ h \circ \Psi_N(z) = R\left[\theta + \beta_1|z|^2 + \dots + \beta_N|z|^{2N}\right]z + O\left(|z|^{2N+2}\right)$$

This iterative process suggests a tentative proof for the stability of $z_* = 0$. Assume we are lucky and the ~~composition~~

$$\cancel{\psi_1 \circ \psi_2 \circ \dots \circ \psi_N} \text{ map } \psi_N$$

converges as $N \to \infty$ to some diffeomorphism ψ. The ~~sequence~~ numbers $\beta_1, \beta_2 \dots$ are independent of N and perhaps the power series

$$\theta + \beta_1 \xi + \dots + \beta_N \xi^N + \dots$$

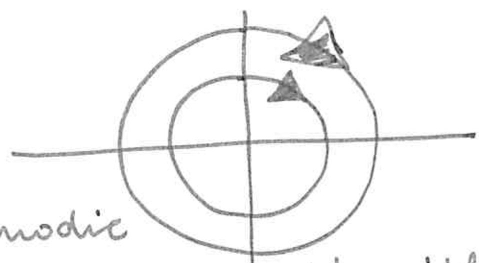
would converge to a function $\phi(\xi)$. Then we could expect

$$\psi^{-1} \circ h \circ \psi(z) = R[\phi(|z|^2)]z.$$

The origin is stable for $\hat{h}(z) = R[\phi(|z|^2)]z$ and so the same should be true for h.

Typically this program will fail. A typical area preserving analytic map will have a countable set of periodic points but $\hat{h}$ has many continua of periodic points and so they cannot be conjugate.

Dynamics of $\hat{h}$:



Invariant circles, they are composed by periodic points when $\phi(|z|^2)$ is commensurable with 2π.

5.2 Some consequences of the KAM method

As a corollary of Moser's small twist theorem it can be proved that $z_* = 0$ is stable if some β_N does not vanish. See [SM].

Russmann proved, using also the KAM method, that if the number $\frac{\theta}{2\pi}$ satisfies a Diophantine condition and $\beta_N = 0$ for each $N \geq 1$ then h is conjugate to the rotation $R[\theta]$. See [Rus]. In particular $z_* = 0$ is stable.

We state as corollaries two consequences of these results.

<u>Corollary 5.1</u> If $h'(0) \sim R[\theta]$ in $Sp(\mathbb{R}^2)$ with

$$\theta \neq \frac{2k\pi}{n}, \quad n = 1, 2, 3, 4$$

and

$$\beta_1 \neq 0$$

then $z_* = 0$ is stable.

<u>Corollary 5.2</u> If $h'(0) \sim R[\theta]$ in $Sp(\mathbb{R}^2)$ and $\frac{\theta}{2\pi}$ satisfies a Diophatine condition then $z_* = 0$ is stable.

The results on the pendulum of variable length and the quadratic equation (presented in the first lesson) were obtained via Corollary 5.1 and formula (*). Indeed it was an extension of this corollary which also deals with strong resonances. The result on the forced pendulum equation is based on the second corollary.

5.3. Some remarks on Diophantine numbers

A number $x \in \mathbb{R} \setminus \mathbb{Q}$ is called Diophantine if there exists two positive constants $\gamma > 0$ and $\sigma > 0$ such that

$$\left| x - \frac{p}{q} \right| \geq \frac{\gamma}{q^\sigma} \quad \text{for each } \frac{p}{q} \in \mathbb{Q} \text{ with } q \geq 1.$$

The class composed by those numbers with fixed constants will be indicated by $DC(\gamma, \sigma)$. Also

$$DC_\sigma = \bigcup_{\gamma > 0} DC(\gamma, \sigma).$$

For $\sigma < 2$ the set DC_σ is empty. For $\sigma \geq 2$ the set DC_σ has an interesting structure. From the point of view of category it is a small set but from the point of view of measure theory is a big set when $\sigma > 2$.

Given γ and σ,

$$DC(\gamma, \sigma) = \mathbb{R} \setminus \bigcup_{q=1}^{\infty} \bigcup_{p \in \mathbb{Z}} \left] \frac{p}{q} - \frac{\gamma}{q^\sigma}, \frac{p}{q} + \frac{\gamma}{q^\sigma} \right[$$

Then $DC(\gamma, \sigma)$ is closed in $\mathbb{R}$ and does not contain any rational number. Then $DC(\gamma, \sigma)$ is closed and has empty interior. Since

$$DC_\sigma = \bigcup_{n=1}^{\infty} DC\left(\frac{1}{n}, \sigma\right)$$

we deduce that DC_σ is of first category.

Let us now assume $\sigma > 2$. We prove that $DC_\sigma \cap [0,1]$ has measure one. From here it is easy to deduce that

DC_σ has full measure in $\mathbb{R}$.

From

$$[0,1] \setminus DC(\gamma,\sigma) \subseteq \bigcup_{q=1}^{\infty} \bigcup_{p=0}^{q} \left] \frac{p}{q} - \frac{\gamma}{q^\sigma}, \frac{p}{q} + \frac{\gamma}{q^\sigma} \right[$$

we deduce that

$$\mu\left([0,1] \setminus DC(\gamma,\sigma)\right) \leq \sum_{q=1}^{\infty} \frac{(q+1)\,2\gamma}{q^\sigma} = S_q \gamma$$

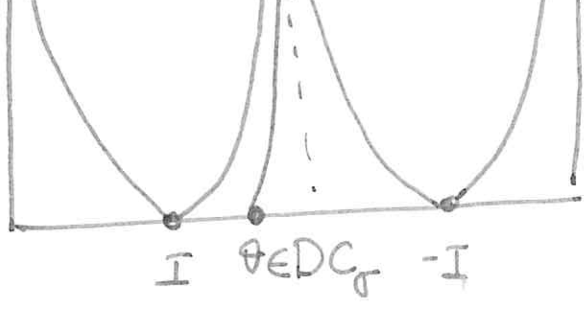
where $S_q = 2 \sum_{q=1}^{\infty} \frac{q+1}{q^\sigma} < \infty$ if $\sigma > 2$.

Therefore

$$\mu\left([0,1] \setminus DC_\sigma\right) \leq \mu\left([0,1] \setminus DC(\gamma,\sigma)\right) \leq S_q \gamma \to 0$$

as $\gamma \to 0$.

<u>Exercise 5.1</u> Consider the Haar measure in the symplectic group $Sp(\mathbb{R}^2)$ and let $\mathcal{E}$ be the open subset of elliptic matrices. Prove that there exists a subset $\hat{\mathcal{E}} \subset \mathcal{E}$ of full measure in $\mathcal{E}$ such that if $h'(0) \in \hat{\mathcal{E}}$ then $z_* = 0$ is stable.



6. A result with proof

Consider the equation

$$(\mathcal{E}) \qquad \ddot{x} + \psi(x) = p(t) + \lambda$$

where $\psi : \mathbb{R} \to \mathbb{R}$ is analytic and satisfies

(i) For some $n = 0, 1, 2, \dots$

$$n^2 < \alpha \leq \psi'(x) \leq \beta < (n + \tfrac{1}{2})^2, \quad x \in \mathbb{R}$$

(ii) The limits $\psi'(\pm\infty) = \lim_{x \to \pm\infty} \psi'(x)$ exist and

$$\psi'(+\infty) \neq \psi'(-\infty).$$

The function $p \in C(\mathbb{T})$ is arbitrary but fixed and $\lambda \in \mathbb{R}$ is a parameter.

Then, in the above conditions, the equation has a stable 2π-periodic solution for almost every $\lambda \in \mathbb{R}$.

Remarks 1. Under the less restrictive condition

$$n^2 < \alpha \leq \psi'(x) \leq \beta < (n+1)^2$$

there exists a unique 2π-periodic solution. This was proved by Loud (1967) and there are also earlier results for Hammerstein's equations which are related.

2. The condition (i) can be replaced by

$$(i)^* \qquad (n + \tfrac{1}{2})^2 < \alpha \leq \psi'(x) \leq \beta < (n+1)^2.$$

The proof will be divided in three steps :

1. Existence and uniqueness. This is very well known and there are many possible proofs (Contraction principle, Global inverse function theorem, Variational methods, ...) We choose a proof that will be useful for the following steps.
2. Linearized stability This will be a consequence of a very old stability criterion for Hill's equation (Krein attributes it to Zhukovskii)
3. Nonlinear stability This will be the key step.

6.1 Existence and uniqueness

We start with two results on linear equations. The proofs are in the Appendix.

Lemma 6.1 Assume that $a \in L^\infty(\mathbb{T})$ satisfies

$$n^2 < \alpha \leq a(t) \leq \beta < (n+1)^2 \quad \text{a.e. } t \in \mathbb{R}.$$

Then $y = 0$ is the only 2π-periodic solution of

$$\ddot{y} + a(t) y = 0.$$

Lemma 6.2 Assume that a is as before and $b \in L^\infty(\mathbb{T})$. Then there exists a number $K_1 = K_1(\alpha, \beta) > 0$ such that the only 2π-periodic solution of

$$\ddot{y} + a(t) y = b(t)$$

satisfies $\quad \|y\|_{W^{2,\infty}} \leq K_1 \|b\|_{L^\infty}.$

In this part it is sufficient to assume $\Psi \in C^1(\mathbb{R})$ and
$$n^2 < \alpha \leq \Psi'(x) \leq \beta < (n+1)^2.$$

<u>Uniqueness</u> Assume that $x_1 \neq x_2$ are two 2π-periodic solutions of $(\mathcal{E})$ and define

$$a(t) = \begin{cases} \dfrac{\Psi(x_1(t)) - \Psi(x_2(t))}{x_1(t) - x_2(t)} & \text{if } x_1(t) \neq x_2(t) \\ \Psi'(x_1(t)) & \text{otherwise.} \end{cases}$$

Then $a(t)$ is in the conditions of Lemma 6.1 and $y = x_1 - x_2$ is a 2π-periodic solution of $\ddot{y} + a(t) y = 0$. This is a contradiction.

<u>Existence</u> Consider the homotopy

$$(\mathcal{E}_\varepsilon) \qquad \ddot{x} + \Psi(x) = \varepsilon p(t) + \lambda, \quad \varepsilon \in [0,1]$$

and let us define
$$E = \{\varepsilon \in [0,1] : \text{there exists a } 2\pi\text{-periodic solution}\}.$$
Since Ψ is a diffeomorphism of $\mathbb{R}$, the constant $x = \Psi^{-1}(\lambda)$ is a solution for $\varepsilon = 0$. Hence $0 \in E$.

<u>E is open in $[0,1]$</u>

Given $\varepsilon_0 \in E$ let $x_*(t)$ be a 2π-periodic solution for $\varepsilon = \varepsilon_0$.
The linearized equation around $x_*(t)$ is
$$\ddot{y} + \Psi'(x_*(t)) y = 0.$$
From Lemma 6.1 we deduce that the number 1 is not a Floquet multiplier. This implies that there exists a 2π-periodic solution $x(t) = x_*(t) + O(\varepsilon)$ for ε close to ε_0.

<u>E is closed</u>

Given $\varepsilon_n \to \varepsilon_*$ with $\varepsilon_n \in E$, we find a 2π-periodic solution $x_n(t)$ of $(\mathcal{E}_{\varepsilon_n})$. It also satisfies the linear equation

$$\ddot{y} + a_n(t)\, y = b_n(t)$$

with $a_n(t) = \begin{cases} \dfrac{\Psi(x_n(t)) - \Psi(0)}{x_n(t)} & \text{if } x_n(t) \neq 0 \\ \Psi'(x_n(t)) & \text{otherwise} \end{cases}$

$b_n(t) = \varepsilon_n p(t) + \lambda - \Psi(0)$. From Lemma 6.2 we deduce that

$$\|x_n\|_{C^2} \leq K_1 \|b_n\|_{L^\infty} \leq K_1 \left[\|p\|_{L^\infty} + |\lambda - \Psi(0)| \right].$$

By Ascoli theorem we extract a subsequence x_k converging to a solution of $(\mathcal{E}_{\varepsilon_*})$. Hence $\varepsilon_* \in E$.

From now on the unique 2π-periodic solution of $(\mathcal{E})$ will be denoted by $x(t,\lambda)$. We are going to prove that the function

$$\lambda \in \mathbb{R} \longmapsto (x(0,\lambda), \dot{x}(0,\lambda)) \in \mathbb{R}^2$$

is analytic.

To this end we introduce the Poincaré map

$$P_\lambda : \mathbb{R}^2 \to \mathbb{R}^2, \quad (x_0, v_0) \longmapsto (x(2\pi; x_0, v_0), \dot{x}(2\pi; x_0, v_0))$$

and notice that $P = P_\lambda(x_0, v_0)$ is analytic as a function of the three arguments $(\lambda, x_0, v_0) \in \mathbb{R}^3$. The possible lack of smoothness in t does not play a role because we are freezing the time $(t = 0)$.

The periodic problem is equivalent to the equation

$$\Phi(x_0, v_0, \lambda) = (id - P_\lambda)(x_0, v_0) = 0.$$

This can be seen as a problem of implicit functions if we seek the solution in the form $x_0 = x_0(\lambda)$, $v_0 = v_0(\lambda)$.

Note that, by uniqueness, $x_0 = x(0,\lambda)$, $v_0 = \dot{x}(0,\lambda)$.

To check the transversality condition we observe that

$$\frac{\partial \Phi}{\partial (x_0, v_0)} = I - M$$

where the derivative is evaluated at the solution and M is the monodromy matrix associated to

$$\ddot{y} + \psi'(x(t,\lambda))y = 0.$$

By Lemma 6.1 we know that 1 is not an eigenvalue of M and so the implicit function theorem (real analytic version) can be applied at each point $(x(0,\lambda), \dot{x}(0,\lambda), \lambda)$

6.2 Linearized stability

The key is the following stability criterion for Hill's eq:

Assume that $a \in C(\mathbb{T})$ satisfies

$$n^2 < \alpha \leq a(t) \leq \beta < \left(n + \tfrac{1}{2}\right)^2.$$

Then $\ddot{y} + a(t)y = 0$ is stable.

This is the classical statement but we will see that the proof gives some useful additional information.

Let

$$\Phi(t) = \begin{pmatrix} y_1(t) & y_2(t) \\ \dot{y}_1(t) & \dot{y}_2(t) \end{pmatrix}$$

be the matrix solution with solutions $y_1(t)$, $y_2(t)$ satisfying

$$y_1(0) = \dot{y}_2(0) = 1, \quad \dot{y}_1(0) = y_2(0) = 0.$$

The stability of the equation is equivalent to the stability of the monodromy matrix $M = \Phi(2\pi) \in Sp(\mathbb{R}^2)$. We shall prove that the trace satisfies $|\operatorname{tr} M| < 2$ and so M is <u>elliptic</u>.

<u>Lemma 6.3</u> Assume that $a \in C(\mathbb{T})$ satisfies

$$n^2 < \alpha \leq a(t) \leq \beta < \left(n + \tfrac{1}{2}\right)^2.$$

Then $\ddot{y} + a(t)y = 0$ has no periodic solutions of period 4π different from $y = 0$.

This is a direct consequence of Lemma 6.1 after changing the time scale.

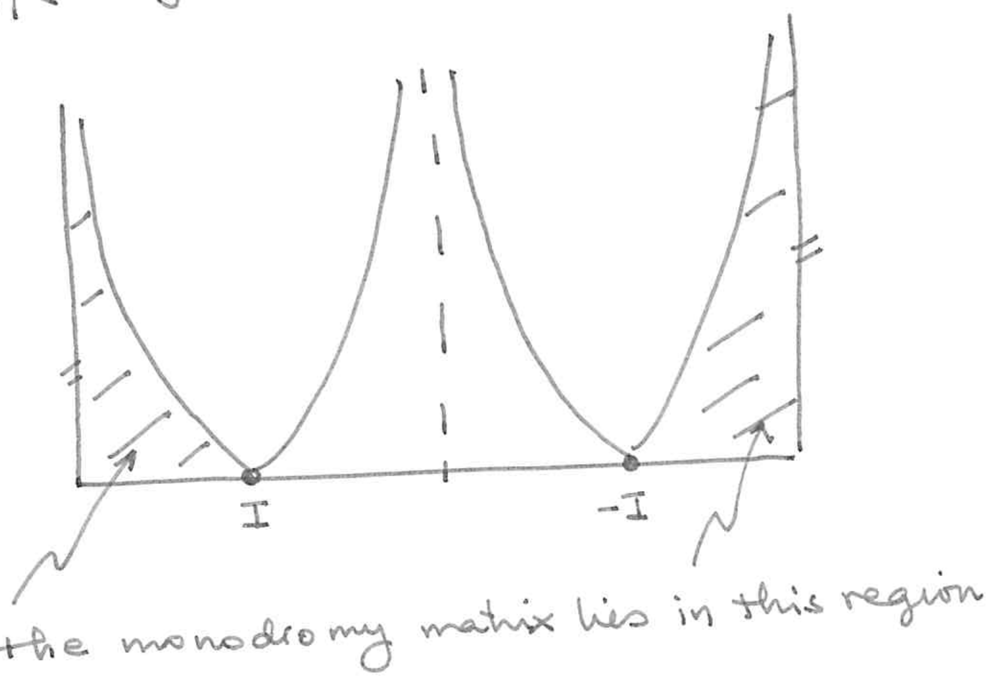
Consider the homotopy of equations

$$\ddot{y} + \left(\lambda a(t) + (1-\lambda)\alpha_*\right)y = 0, \quad \lambda \in [0,1]$$

with α_* a fixed number lying on $[a,b]$. Let $\Phi(t,\lambda)$ be the matrix solution as before and

$$\Delta(\lambda) = \operatorname{tr} \Phi(2\pi, \lambda).$$

The discriminant function $\Delta(\lambda)$ is continuous and we can apply Lemma 6.3 to the equation with λ. This implies $\Delta(\lambda) \neq \pm 2$ for each $\lambda \in [0,1]$. For $\lambda = 0$ the equation $\ddot{y} + \alpha_* y = 0$ can be solved and $|\Delta(0)| < 2$. Then $|\Delta(\lambda)| < 2$ for each λ and, in particular, $|\Delta(1)| < 2$.



6.3. Nonlinear stability

We start with a result on analytic functions.

Lemma 6.4 Let $f: \mathbb{R} \to \mathbb{R}$ be a non-constant analytic function and let $Z \subset \mathbb{R}$ be a set of zero measure. Then also $f^{-1}(Z)$ has zero measure.

Proof The set $\Lambda = \{\lambda \in \mathbb{R} : f'(\lambda) = 0\}$ is discrete and closed. In particular $\mathbb{R} \setminus \Lambda = \bigcup_i I_i$ where I_i is an open interval and the union is disjoint. Define $f_i = f|_{I_i}$. This is a diffeomorphism from I_i onto

$f(I_i)$ and so $f_i^{-1}(Z_1)$ has zero measure. Finally we observe that

$$f^{-1}(Z_1) \subset \bigcup_i f_i^{-1}(Z_1) \cup \Lambda.$$

The set of indexes $I = \{i\}$ is at most countable. Also Λ is countable, implying $\mu(\Lambda) = 0$.

Let $x(t,\lambda)$ be the 2π-periodic solution of $(\mathcal{E})$. We will prove that the fixed point $(x(0,\lambda), \dot{x}(0,\lambda))$ is stable with respect to P_λ. The derivative

$$L = P_\lambda'(x(0,\lambda), \dot{x}(0,\lambda))$$

is the monodromy matrix of

$$\ddot{y} + \psi'(x(t,\lambda))y = 0.$$

From the previous section we know that

$$L \sim R[\theta] \text{ in } Sp(\mathbb{R}^2).$$

The trace is an invariant and so the trace of L is precisely $2\cos\theta$.

Let $\Phi(t,\lambda)$ be the matrix solution of the linearized equation, we define the function

$$\Delta(\lambda) = \operatorname{tr} \Phi(2\pi, \lambda).$$

This is an analytic function and

$$\frac{\theta}{2\pi} \in DC_\sigma \iff \Delta(\lambda) \in \mathcal{D}_\sigma$$

where

$$\mathcal{D}_\sigma = \left\{ 2\cos\theta : \frac{\theta}{2\pi} \in DC_\sigma \right\}.$$

Here we are using that $2\cos\theta$ defines diffeomorphisms $]0,\pi[\approx]-2,2[$ and $]\pi, 2\pi[\approx]-2,2[$. If we define $f(x) = 2\cos(2\pi x)$ then $\mathcal{D}_\sigma = f(DC_\sigma)$. Then, if $\sigma > 2$, $\mathcal{D}_\sigma$ has full measure in $]-2,2[$.

Unless Δ were constant we can now say that

$$\Delta^{-1}\left( ]-2,2[\setminus \mathcal{D}_\sigma \right)$$

has zero measure. This implies that $\frac{\theta}{2\pi} \in DC_\sigma$ for almost every $\lambda \in \mathbb{R}$ and the conclusion follows from Corollary 5.2.

We prove that $\Delta(\lambda)$ is not constant in three steps:

(1) $\quad x(t,\lambda) = \psi^{-1}(\lambda) + O(1)$ as $|\lambda| \to \infty$, uniformly in $t \in \mathbb{R}$.

Let $\mu = \psi^{-1}(\lambda)$ and $y(t) = x(t) - \mu$. Then $y(t)$ is a 2π-periodic solution of

$$\ddot{y} + \psi(y+\mu) - \psi(\mu) = p(t).$$

In particular $y(t)$ is also a solution of

$$\ddot{y} + a_\mu(t) y = p(t) \quad \text{with} \quad a_\mu = \begin{cases} \dfrac{\Psi(y(t)+\mu) - \Psi(\mu)}{y(t)}, & y \neq 0 \\ \Psi'(\mu) & y = 0 \end{cases}$$

We apply again Lemma 6.2 to deduce that

$$\| y(\cdot, \lambda) \|_{C^2} \leq K_1 \| p \|_\infty$$

(2) $\quad \Delta(\lambda) \longrightarrow 2 \cos\left(2\pi \Psi'(\pm\infty)^{1/2}\right)$ as $\lambda \to \pm\infty$

From step 1 we deduce that $x(t,\lambda) \to \pm\infty$ as $\lambda \to \pm\infty$ uniformly in t. Then

$$\Psi'(x(t,\lambda)) \to \Psi'(\pm\infty) \quad \text{as } \lambda \to \pm\infty$$

uniformly in $t \in \mathbb{R}$. By continuous dependence $\Delta(\lambda) \to tr(M_\pm)$ where $M_\pm$ is the monodromy matrix of $\ddot{y} + \Psi'(\pm\infty) y = 0$

(3) $\quad tr(M_+) \neq tr(M_-)$ because $2\pi \Psi'(+\infty)^{1/2}$ and $2\pi \Psi'(-\infty)^{1/2}$ lie on the interval $]2n\pi, (2n+1)\pi[$.

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