

**NECESSARY AND SUFFICIENT CONDITIONS FOR THE OSCILLATION OF DELAY  
DIFFERENTIAL EQUATION WITH A PIECEWISE CONSTANT ARGUMENT**

H.A. AGWO  
Department of Mathematics  
Faculty of Education  
Ain Shams University  
Roxy ,Cairo , Egypt.

(Received August 13, 1996 and in revised form March 18, 1997)

**ABSTRACT:** The characteristic equation for an equation with continuous and piecewise constant argument in the form

$$\dot{x}(t) + p x(t - \tau) + q x([t - k]) = 0 \text{ where } p, q \in \mathbb{R}, \tau \in \mathbb{R}^+ \text{ and } k \in \mathbb{N}.$$

is presented , which when  $q=0$  reduces to

$$f(\lambda) = \lambda + e^{-\lambda\tau} = 0$$

and when  $p=0$  reduces to

$$\lambda - 1 + q \lambda^{-k} = 0.$$

Also, the necessary and sufficient conditions for oscillation are obtained.

**KEY WORDS:** Oscillations , Delay differential equations.

**1991 AMS SUBJECT CLASSIFICATION CODES:** 34k15 ; 39A10.

## 1. INTRODUCTION

The study of equations with piecewise constant argument was originated by the work of Wiener and his collaborators. See [1,2,3,4,5 and 6] and the references cited therein . In addition to its own interest this area has stimulated much activity in the study of delay difference equations.

As usual , a solution  $x(t)$  is called oscillatory if it has arbitrarily large zeros .Otherwise , the solution is called nonoscillatory.An equation is called oscillatory if all its solutions are oscillatory.

Let  $[.]$  denote the greatest-integer function,  $\mathbb{N}$  the set of non-negative integers and  $\mathbb{R}$  the set of real numbers.

Consider

$$\dot{x}(t) + p x(t - \tau) + q x([t - k]) = 0 \quad (1.1)$$

where  $p, q \in \mathbb{R}, \tau \in \mathbb{R}^+$  and  $k \in \mathbb{N}$ .

By a solution of Eqn.(1.1), we mean a function  $x$  which is defined on the set  $\{-k, \dots, -1, 0\} \cup [-\tau, \infty)$  and satisfies the following properties:

- (a)  $x$  is continuous on  $[-\tau, \infty)$ .
- (b) the derivative  $\dot{x}$  exists at each point  $t \in (0, \infty)$  with the possible exception of the points  $t \in \mathbb{N}$ , where one side derivatives exist.
- (c) Eqn.(1.1) is satisfied on each interval  $[n, n+1]$  for  $n \in \mathbb{N}$ .

Let  $\phi \in C([- \tau, 0], \mathbb{R})$  and  $a_{-k}, \dots, a_{-1}, a_0$  be given real numbers such that

$$a_{-j} = \phi(-j) \text{ for } j=0, 1, 2, \dots, k, \quad (1.2)$$

then one can show that Eqn. (1.1) has a unique solution satisfying the initial conditions

$$x(t) = \phi(t) \quad -\tau \leq t \leq 0 \quad (1.3a)$$

$$x(-j) = a_{-j} \quad j=0, 1, \dots, k. \quad (1.3b)$$

When  $q=0$ , Eqn. (1.1) reduces to

$$\dot{u}(t) + p u(t - \tau) = 0 \quad (1.4)$$

which is oscillatory if and only if its characteristic equation

$$f(\lambda) = \lambda + e^{-\lambda\tau} = 0 \quad (1.5)$$

has no real roots, or equivalently, to

$$p\tau > \frac{1}{e}. \quad (1.6)$$

On the other hand, when  $p=0$ , Eqn.(1.1) reduces to

$$\dot{v}(t) + q v([t - k]) = 0 \quad (1.7)$$

which is oscillatory if and only if the following equation

$$\lambda - 1 + q \lambda^{-k} = 0 \quad (1.8)$$

has no positive real roots, or equivalently,

$$q > \frac{k^k}{(k+1)^{k+1}} \quad , k \geq 1 \quad (1.9a)$$

$$q \geq 1 \quad , k = 0 \quad (1.9b)$$

An open question arises ( see [4] ,p. 223) for obtaining a characteristic equation for equation (1.1) which reduces to Eqn.(1.5) when  $q=0$  and reduces to Eqn. (1.8) when  $p=0$  and also obtaining the necessary and sufficient conditions for oscillation of all solutions of

$$\dot{x}(t) + p x(t - 1) + q x([t - 1]) = 0 \quad (1.10)$$

## 2. THE MAIN RESULTS

In the following , a characteristic equation associated with equation (1.1) will be presented in Theorem 2.1 . Also the necessary and sufficient conditions for oscillation are obtained through Theorems 2.2 and 2.3 .

**THEOREM 2.1.** The characteristic equation associated with equation (1.1) is

$$f(\lambda) = \lambda - 1 + \frac{p \lambda^{-\tau}}{\ln \lambda} (\lambda - 1) + q \lambda^{-k} = 0 \quad (2.1)$$

which reduces to Eqn. (1.5) when  $q=0$  and reduces to Eqn. (1.8) when  $p=0$ .

**PROOF:** Consider Eqn.(1.1) and assume that the initial conditions (1.3a) and (1.3b) are satisfied .For  $t \in [n, n+1]$  , we have  $[t-k] = n-k$  and one can write

$$\dot{x}(t) + p x(t-\tau) + q a_{n-k} = 0 \quad , \quad t \in [n, n+1] \quad (2.2a)$$

$$x(n) = a_n \quad , \quad n \in \mathbb{N} \quad (2.2b)$$

Integrating (2.2a) from  $n$  to  $t$  , we get

$$x(t) - a_n + p \int_n^t x(s-\tau) ds + q a_{n-k} (t-n) = 0 . \quad (2.3)$$

By using the continuity of  $x(t)$  as  $t \rightarrow n+1$  , we find

$$a_{n+1} - a_n + p \int_n^{n+1} x(s-\tau) ds + q a_{n-k} = 0 . \quad (2.4)$$

Assume that  $x(t) = e^{\lambda t}$  ,  $t \in [n, n+1]$  , then from (2.4) ,we get

$$f(\lambda) = e^{\lambda} - 1 + \frac{p e^{-\lambda \tau}}{\lambda} (\lambda - 1) + q e^{-\lambda k} = 0 \quad (2.5)$$

Putting  $e^{\lambda} = \gamma$  in Eqn.(2.5),then

$$F(\gamma) = \gamma - 1 + \frac{p \gamma^{-\tau}}{\ln \gamma} (\gamma - 1) + q \gamma^{-k} = 0 . \quad (2.6)$$

and consequently Eqn.(2.6) has no positive real roots if and only if Eqn.(2.5) has no real roots.Assume that Eqn.(2.5) has no real roots , then  $\lambda \neq 0$  , and consequently  $\gamma \neq 1$  . If  $p=0$  , then Eqn. (2.6) reduces to Eqn.(1.8),also if  $q=0$  ,then Eqn.(2.6) reduces to Eqn.(1.5) .

**THEOREM 2.2.** Equation (1.1) is oscillatory if and only if its characteristic equation (2.6) has no positive real roots.

**PROOF:** Assume that the characteristic equation (2.6) has a positive real root  $\gamma_0$  , then  $\gamma_0'$  is a solution of Eqn.(2.4) which is a nonoscillatory solution and consequently Eqn.(1.1) is not oscillatory .On the other hand , assume that  $x(t) > 0 \quad \forall t \in [n, n+1]$  for sufficiently large  $n$  and  $F(\gamma)$  has no positive real roots .As  $F(\infty) = \infty$  , it follows that  $F(\gamma) > 0 \quad \forall \gamma \in (0, \infty)$  .For seeking the contradiction , choose :

- (i)  $p \leq 0$  and  $q \leq 0$  then  $F(\gamma) < 0 \quad \forall \gamma \in (0, 1)$  ,
- (ii)  $p \geq 0$  ,  $q < 0$  with  $p < |q|$  and  $\tau \leq k$  then  $F(\gamma) < 0 \quad \forall \gamma \in (0, 1)$  ,
- (iii)  $p < 0$  ,  $q \geq 0$  with  $q < |p| (1 - 1/e)$  and  $\tau = k$  then  $F(1/e) < 0$  ,
- (iv)  $p \geq 0$  ,  $q \geq 0$  with  $p + q \leq 1/8e^k$  and  $\tau \leq k$  then  $F(1/e) < 0$  ,

which is a contradiction.

**THEOREM 2.3.** If  $p, q \in \mathbb{R}^+$  , then all solutions of equation (1.1) are oscillatory if and only if

$$p\tau + q \frac{(k+1)^{k+1}}{k^k} > 1 \quad , \quad k \geq 1 \quad (2.7)$$

**PROOF:** Assume that Eqn.(1.1) has a nonoscillatory solution ,then the characteristic Eqn.(2.6) has a positive real root  $\gamma_0 \in (0, 1)$  . Otherwise  $F(\gamma_0) > 0 \quad \forall \gamma_0 \in [1, \infty)$  and therefore , we have

$$F(\gamma_0) = \gamma_0 - 1 + \frac{p\gamma_0^{-\tau}}{\ln \gamma_0} (\gamma_0 - 1) + q\gamma_0^{-k} = 0, \gamma_0 \in (0,1)$$

and then

$$\begin{aligned} 0 &= (\gamma_0 - 1) \left\{ 1 + \frac{p\gamma_0^{-\tau}}{\ln \gamma_0} + q\gamma_0^{-k} / (\gamma_0 - 1) \right\} \\ 0 &= 1 + \frac{p\gamma_0^{-\tau}}{\ln \gamma_0} + q\gamma_0^{-k} / (\gamma_0 - 1) \\ &\leq 1 - pe\tau - q \frac{(k+1)^{k+1}}{k^k} \end{aligned}$$

which is a contradiction .On the other hand ,assume that

$$pe\tau + q \frac{(k+1)^{k+1}}{k^k} \leq 1, k \geq 1.$$

Now , we study the following cases:

(1)  $q=0, p>0$ .

Since  $F(\gamma) > 0, \forall \gamma \in (1, \infty)$  and  $F(e^{-\frac{1}{\tau}}) \leq 0$  ,then there exists  $\gamma_1 \in \mathfrak{R}^+$  such that  $F(\gamma_1) = 0$  . i.e. the characteristic equation has a positive real root and consequently equation (1.1) is not oscillatory.

(2)  $p=0, q>0$ .

In this case ,  $F(\gamma) > 0, \forall \gamma \in (1, \infty)$  and  $F(\frac{k}{k+1}) \leq 0$ .Therefore , the characteristic equation has a positive real root and then equation(1.1) has a nonoscillatory solution.

(3)  $p>0, q>0$ .

Since  $pe\tau + q \frac{(k+1)^{k+1}}{k^k} \leq 1$ ,

then,

$$q \frac{(k+1)^{k+1}}{k^k} + \frac{p \frac{(k+1)^{k+1}}{k^k}}{\ln(\frac{k}{k+1})} < pe\tau + q \frac{(k+1)^{k+1}}{k^k} \leq 1, k \geq 1. \quad (2.8)$$

It is clear that the characteristic equation has no real roots in  $(1, \infty)$  and  $F(\gamma) > 0$ ,but

$$\begin{aligned} F(\frac{k}{k+1}) &= \frac{k}{k+1} - 1 + \frac{p \frac{(k+1)^k}{k^k}}{\ln(\frac{k}{k+1})} + q \frac{(k+1)^k}{k^k} \\ &= -\frac{1}{k+1} + \frac{q}{(k+1)} \frac{(k+1)^{k+1}}{k^k} + \frac{p}{k+1} \frac{\frac{(k+1)^{k+1}}{k^k}}{\ln(\frac{k}{k+1})} \end{aligned}$$

From (2.8),it follows that  $F(\frac{k}{k+1}) \leq 0$  and

consequently equation (1.1) has a nonoscillatory solution.

**REMARK.** If  $\tau = k = 1$  and  $p, q \in \mathfrak{R}^+$  ,then  $pe + 4q > 1$  is a necessary and sufficient condition for oscillation of

$$\dot{x}(t) + px(t-1) + qx([t-1]) = 0.$$

## REFERENCES

- [1] COOKE, K.L. and WIENER,J., Retarded differential equations with piecewise constant delays , *J. Math. Anal. and Appl.* **99** (1984), 265- 294.
- [2] COOKE, K.L. and WIENER,J., Neutral differential equations with piecewise constant argument, *Bulletino Unione Mathematica Italiana* **1-B** (1987), 321-345.
- [3] GROVE, E.A. , GYÖRI,I.,and LADAS,G.,On the characteristic equations for equations with continuous and piecewise constant arguments ,*Radovi Mathematicki* **5** (1990), 271- 281.
- [4] GYÖRI,I.,and LADAS,G. , Oscillation Theory of Delay Differential Equations with Applications , *Clarendon Press, Oxford ,1991.*
- [5] WIENER,J. and COOKE, K.L., Oscillations in systems of differential equations with piecewise constant argument , *J. Math. Anal. and Appl.* **137** (1989) , 221-239 .
- [6] WIENER, J., Generalized Solutions of Functional Differential Equations , *World Scientific , Singapore , 1993 .*

## Special Issue on Modeling Experimental Nonlinear Dynamics and Chaotic Scenarios

### Call for Papers

Thinking about nonlinearity in engineering areas, up to the 70s, was focused on intentionally built nonlinear parts in order to improve the operational characteristics of a device or system. Keying, saturation, hysteretic phenomena, and dead zones were added to existing devices increasing their behavior diversity and precision. In this context, an intrinsic nonlinearity was treated just as a linear approximation, around equilibrium points.

Inspired on the rediscovering of the richness of nonlinear and chaotic phenomena, engineers started using analytical tools from "Qualitative Theory of Differential Equations," allowing more precise analysis and synthesis, in order to produce new vital products and services. Bifurcation theory, dynamical systems and chaos started to be part of the mandatory set of tools for design engineers.

This proposed special edition of the *Mathematical Problems in Engineering* aims to provide a picture of the importance of the bifurcation theory, relating it with nonlinear and chaotic dynamics for natural and engineered systems. Ideas of how this dynamics can be captured through precisely tailored real and numerical experiments and understanding by the combination of specific tools that associate dynamical system theory and geometric tools in a very clever, sophisticated, and at the same time simple and unique analytical environment are the subject of this issue, allowing new methods to design high-precision devices and equipment.

Authors should follow the Mathematical Problems in Engineering manuscript format described at <http://www.hindawi.com/journals/mpe/>. Prospective authors should submit an electronic copy of their complete manuscript through the journal Manuscript Tracking System at <http://mts.hindawi.com/> according to the following timetable:

Manuscript Due	December 1, 2008
First Round of Reviews	March 1, 2009
Publication Date	June 1, 2009

### Guest Editors

**José Roberto Castilho Piqueira**, Telecommunication and Control Engineering Department, Polytechnic School, The University of São Paulo, 05508-970 São Paulo, Brazil; [piqueira@lac.usp.br](mailto:piqueira@lac.usp.br)

**Elbert E. Neher Macau**, Laboratório Associado de Matemática Aplicada e Computação (LAC), Instituto Nacional de Pesquisas Espaciais (INPE), São José dos Campos, 12227-010 São Paulo, Brazil ; [elbert@lac.inpe.br](mailto:elbert@lac.inpe.br)

**Celso Grebogi**, Center for Applied Dynamics Research, King's College, University of Aberdeen, Aberdeen AB24 3UE, UK; [grebogi@abdn.ac.uk](mailto:grebogi@abdn.ac.uk)