

NONLINEAR INTEGRAL INEQUALITY IN TWO INDEPENDENT VARIABLES

P.T. VAZ and S.G. DEO

Department of Mathematics
University Goa
Bambolim, Goa - 403 001
INDIA

(Received May 27, 1986 and in revised form October 28, 1986)

ABSTRACT. In this note, the authors obtain a generalization of the integral inequality of Bihari [1] to a nonlinear inequality in two independent variables. With the aid of this inequality a bound for the solution of a nonlinear partial differential equation is established.

KEYS WORDS AND PHRASES. *Nonlinear integral inequality, submultiplicative function, nonlinear partial differential equation.*

1980 AMS SUBJECT CLASSIFICATION CODE. *Primary 35R45, Secondary 34A40.*

1. INTRODUCTION.

In the qualitative analysis of differential equations integral inequalities play a vital role [2]. An inequality due to Gronwall continues to draw the attention of mathematicians because of its usefulness. The nonlinear generalization of this inequality due to Bihari [1] is as follows:

LEMMA 1. Let $Y(x)$, $F(x)$ be positive continuous functions in $a \leq x \leq b$ and $K \geq 0$, $M \geq 0$, further $W(u)$ a non-negative non-decreasing continuous function for $u \geq 0$. Then the inequality

$$Y(x) \leq K + M \int_a^x F(t) W(Y(t)) dt \quad (a \leq x \leq b)$$

implies the inequality

$$Y(x) \leq G^{-1}(G(K) + M \int_a^x F(t) dt) \quad (a \leq x \leq b' \leq b)$$

where

$$G(u) = \int_{u_0}^u \frac{dt}{W(t)} \quad (u_0 > 0, u \geq 0).$$

This inequality has been further generalized in several directions by Beesack [3].

It has been recently established that the inequalities of this type in two and more independent variables can be profitably employed in the analysis of partial differential equations [4, and references listed therein]. An interesting inequality by Wendroff given without proof in [5] is as follows:

LEMMA 2. Let $J = \{x \mid 0 \leq x \leq X < \infty\}$ and $K = \{y \mid 0 \leq y \leq Y < \infty\}$. Further let $U(x,y)$ be a scalar, non-negative continuous function defined on $J \times K$, then for any arbitrary non-negative constants a, b and c , the integral inequality

$$U(x,y) \leq c + a \int_0^x U(s,y)ds + b \int_0^y U(x,t)dt$$

implies that $U(x,y) \leq c \exp(ax + by + abxy)$.

The proof of this inequality can be constructed by observing that $U \leq P$, where $P(x,y)$ satisfies the equation

$$P(x,y) = c + a \int_0^x P(s,y)ds + b \int_0^y P(x,t)dt.$$

Observe that $P(x,0) = c \exp(ax)$ and $P(0,y) = c \exp(by)$. Now assuming $P(x,y) = \exp(ax + by)q(x,y)$, one can determine the inequality satisfied by $q(x,y)$ which results into the given conclusion.

Lemma 2, in view of Lemma 1, suggests that it is possible to consider a nonlinear generalization of the Wendroff's inequality. We do this in the present paper and further show by an example that the generalization of this kind is truly beneficial in the study of some nonlinear partial differential equations.

2. NOTATION.

Let \mathbb{R} denote the real line. For any rectangle $J \times K$ we define the following classes of functions:

- (i) $C^+(J \times K)$ = the space of continuous functions
 $u : J \times K \rightarrow \mathbb{R}^+$
- (ii) $C_1(\mathbb{R}^+)$ = the space of non-decreasing, non-negative, submultiplicative, continuous functions on \mathbb{R}^+ .
- (iii) $C_2(\mathbb{R}^+)$ = the space of non-decreasing, non-negative, continuous functions on \mathbb{R}^+ and such that for $g_2 \in C_2(\mathbb{R}^+)$ and for any real-valued function $h(x,y)$, $(x,y) \in J \times K$,

$$\frac{g_2(u(x,y))}{h(x,y)} \leq g_2\left(\frac{u(x,y)}{h(x,y)}\right), \quad h(x,y) \geq 1. \quad (2.1)$$

Further, we define

$$G_1(u) = \int_{u_0}^u \frac{dt}{g_1(t)}, \quad (u \geq 0, u_0 > 0). \quad (2.2)$$

Let G_1^{-1} be the inverse of G_1 , $i = 1, 2$.

3. MAIN RESULT.

THEOREM 3.1. Assume that

$$(a) \quad u(x,y) \in C^+(J \times K),$$

$$(b) \quad g_1(u) \in C_1(\mathbb{R}^+),$$

$$(c) \quad g_2(u) \in C_2(\mathbb{R}^+),$$

(d) there exists a $u_0 > 0$ such that $g_1(u) > 0$ and $g_2(u) > 0$ for $u \geq u_0$. Then for any arbitrary non-negative constants a, b and c , with $c \geq 1$, the inequality

$$u(x,y) \leq c + a \int_0^x g_1(u(s,y)) ds + b \int_0^y g_2(u(x,t)) dt, \quad (0 \leq x \leq X, 0 \leq y \leq Y) \quad (3.1)$$

implies, on a nonempty rectangle, the inequality

$$u(x,y) \leq G_1^{-1} \left\{ G_1(c) + ax g_1 [G_2^{-1}(G_2(1) + by)] \right\} G_2^{-1}(G_2(1) + by), \quad (3.2)$$

where $G_i(u)$, $i = 1, 2$, are as defined in (2.2), $(0 \leq x \leq X' \leq X$ and $0 \leq y \leq Y' \leq Y)$.

PROOF. We define

$$h(x,y) = c + a \int_0^x g_1(u(s,y)) ds, \quad (x,y) \in J \times K. \quad (3.3)$$

It is clear that $h(x,y)$ is non-decreasing and $h(x,y) \geq 1$ on $J \times K$.

Inequality (3.1) may be written as

$$u(x,y) \leq h(x,y) + b \int_0^y g_2(u(x,t)) dt. \quad (3.4)$$

Dividing throughout by $h(x,y)$ and using (2.1) of assumption (c) we have

$$\frac{u(x,y)}{h(x,y)} \leq 1 + b \int_0^y g_2\left(\frac{u(x,t)}{h(x,t)}\right) dt. \quad (3.5)$$

For fixed $x \in J$, an application of Lemma 1 yields

$$u(x,y) \leq h(x,y) \cdot G_2^{-1}(G_2(1) + by), \quad (0 \leq x \leq X, 0 \leq y \leq Y' \leq Y) \quad (3.6)$$

Substituting (3.6) in (3.3) and employing submultiplicative property of g_1 we obtain

$$h(x,y) \leq c + a \int_0^x g_1(h(s,y)) g_1(G_2^{-1}(G_2(1) + by)) ds. \quad (3.7)$$

An application of Lemma 1 again, to (3.7), yields a bound for $h(x,y)$ on a nonempty rectangle. The desired inequality now follows by substituting the bound for $h(x,y)$ in (3.6).

REMARK 3.1. In particular, if $b = 0$ and $g_1(u) = u$, then the estimate in (3.2) reduces to

$$u(x,y) \leq G_1^{-1} [G_1(c) + ax].$$

In view of (2.2), it is clear that for fixed $y \in K$, our estimate further reduces to

$$u(x,y) \leq c \exp(ax).$$

Thus, Gronwall's estimate is included in (3.2).

REMARK 3.2. In the case $b = 0$, the estimate in (3.2) reduces to

$$u(x,y) \leq G_1^{-1} [G_1(c) + ax g_1(1)]$$

for each $y \in K$, $0 \leq x \leq X' \leq X$, which is a Bihari-like estimate.

Further, if in (3.1), $a = 0$, then for fixed $x \in J$,

$$u(x,y) \leq c + b \int_0^y g_2(u(x,t)) dt$$

implies

$$\frac{u(x,y)}{c} \leq 1 + b \int_0^y g_2 \left(\frac{u(x,t)}{c} \right) dt, \quad y \in K.$$

An application of Lemma 1 yields

$$u(x,y) \leq c G_2^{-1} [G_2(1) + by],$$

$$(x \in J \text{ is fixed, } 0 \leq y \leq Y' \leq Y)$$

This estimate is the same as that obtained from (3.2) with $a = 0$.

REMARK 3.3. Let $g_i(u) = u$, $i = 1, 2$. Then

$$G_i(u) = \log \frac{u}{u_0}, \quad u \geq 0, \quad u_0 > 0, \quad i = 1, 2.$$

Clearly

$$G_i^{-1}(v) = u_0 \exp(v), \quad i = 1, 2.$$

Hence the estimate (3.2) reduces to

$$\begin{aligned} u(x,y) &\leq u_0 \exp \left[\log \frac{c}{u_0} + ax u_0 \exp \left(\log \frac{1}{u_0} + by \right) \right] \cdot u_0 \exp \left(\log \frac{1}{u_0} + by \right) \\ &\leq c \exp [ax \exp(by) + by] \\ &= c \exp [ax + by + abxy + \text{higher order terms}]. \end{aligned}$$

This estimate is obviously not as sharp as the one obtained in Lemma 2.

4. AN APPLICATION.

Consider the characteristic initial value problem for the nonlinear partial differential equation

$$u_{xy} = u^a u_y + b e^u u_x, \quad a, b \geq 0,$$

$$(0 \leq x \leq X, \quad 0 \leq y \leq Y) \quad (4.1)$$

satisfying the initial values

$$u(x,0) = u(0,y) = u(0,0) = c \geq 1. \quad (4.2)$$

Under the condition (4.2) equation (4.1) can be reformulated in terms of the integral equation

$$\begin{aligned} u(x,y) &= c - \frac{1}{a+1} \int_0^x u^{a+1}(s,0) ds - b \int_0^x e^{u(0,t)} dt \\ &\quad + \frac{1}{a+1} \int_0^y u^{a+1}(s,y) ds + b \int_0^y e^{u(x,t)} dt. \end{aligned} \quad (4.3)$$

Therefore, using the initial - data, we obtain the inequality

$$|u(x,y)| \leq k + \frac{1}{a+1} \int_0^x |u(s,y)|^{a+1} ds + b \int_0^y e^{|u(x,t)|} dt,$$

where $k = (|c| + \frac{|c|^{a+1}X}{a+1} + be|c|_Y)$.

The present inequality is equivalent to (3.1). A direct application of Theorem 3.1 yields

$$|u(x,y)| \leq G_1^{-1} \left[G_1(k) + \frac{x}{a+1} [G_2^{-1}(G_2(1) + by)]^{a+1} \right] \cdot G_2^{-1}(G_2(1) + by)$$

where

$$G_1(u) = \int_0^u \frac{1}{p^{a+1}} dp = -\frac{1}{a} \left[\frac{1}{u^a} - \frac{1}{u_0^a} \right], \text{ and } G_2(u) = \int_0^u \frac{1}{e^p} dp = -[e^{-u} - e^{-u_0}].$$

Therefore,

$$G_1^{-1}(v) = [u_0^{-a} - av]^{-1/a} \text{ and } G_2^{-1}(v) = \log_e [e^{-u_0} - v]^{-1}.$$

Hence,

$$|u(x,y)| \leq \left\{ k^{-a} - \frac{ax}{a+1} [\log(e^{-1} - by)^{-1}]^{a+1} \right\}^{-1/a} \cdot \log(e^{-1} - by)^{-1}.$$

This provides a pointwise estimate for solutions of the given equation (4.1).

REFERENCES

1. BIHARI, I. A Generalization of a Lemma of Bellman and its Application to Uniqueness Problems of Differential Equations, Acta Math. Acad. Sci. Hungar. 7 (1956), 71-94.
2. LAKSHMIKANTHAM, V. and LEELA, S. Differential and Integral Inequalities, Theory and Applications, Vol. I, Academic Press, New York, 1969.
3. BEESACK, P.R. On Integral Inequalities of Bihari Type, Acta Math. Acad. Sci. Hungar. 28(1976), 81-88.
4. CORDUNEANU, A. A Note on the Gronwall Inequality in Two Independent Variables, Journal of Integral Equations 4(1982), 272-276.
5. BECKEMBACK, E.F. and BELLMAN, R. Inequalities, Springer-Verlag, Berlin, 1961.

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	February 1, 2009
First Round of Reviews	May 1, 2009
Publication Date	August 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

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

Celso Grebogi, Department of Physics, King's College, University of Aberdeen, Aberdeen AB24 3UE, UK; grebogi@abdn.ac.uk