

M224

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# Equilibria & linearization

For nonlinear autonomous system:  $\dot{x} = F(x)$

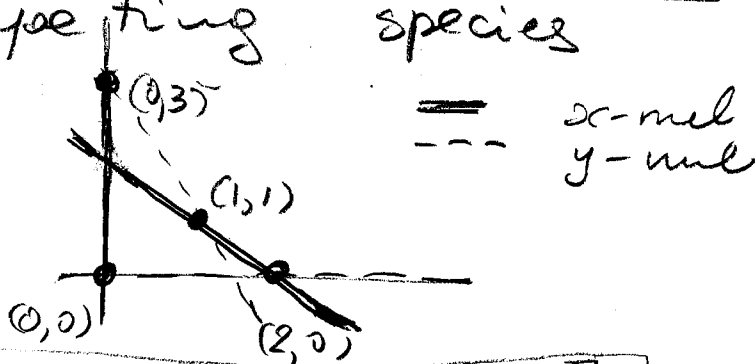
$x = \begin{pmatrix} x \\ y \end{pmatrix}$ ;  $F = \begin{pmatrix} f(x,y) \\ g(x,y) \end{pmatrix}$  compute equilibria

$F(x) = \vec{0} \Rightarrow x_0, x_1, \dots$  and linearize  $F$  at each one

$x(t) \approx x_0 + U(t)$ , where  $\dot{U} = AU$  with Jacobian matrix  $A = \begin{bmatrix} f_x & f_y \\ g_x & g_y \end{bmatrix} \Big|_{x_0}$  approximate linear DS

Example: competing species

$$\begin{cases} \dot{x} = 2x(1 - x/2) - xy \\ \dot{y} = 3y(1 - y/3) - 2xy \end{cases}$$



Jacobian:  $F' = \begin{bmatrix} (2-2x-y) & -x \\ -2y & (3-2x-2y) \end{bmatrix}$

Equil.	A	eigens	Approx. $x \approx$	Stab. type	Phase-plot
(0,0)	$\begin{bmatrix} 2 & 0 \\ 0 & 3 \end{bmatrix}$	$\begin{matrix} 2 & 3 \\ \begin{pmatrix} 1 \\ 0 \end{pmatrix} & \begin{pmatrix} 0 \\ 1 \end{pmatrix} \end{matrix}$	$c_1 e^{2t} \begin{pmatrix} 1 \\ 0 \end{pmatrix} + c_2 e^{3t} \begin{pmatrix} 0 \\ 1 \end{pmatrix}$	source / unst.	
(2,0)	$\begin{bmatrix} -2 & -2 \\ 0 & -1 \end{bmatrix}$	$\begin{matrix} -2 & -1 \\ \begin{pmatrix} 1 \\ 0 \end{pmatrix} & \begin{pmatrix} -2 \\ 1 \end{pmatrix} \end{matrix}$	$\begin{pmatrix} 2 \\ 0 \end{pmatrix} + c_1 e^{-2t} \begin{pmatrix} 1 \\ 0 \end{pmatrix} + c_2 e^{-t} \begin{pmatrix} -2 \\ 1 \end{pmatrix}$	sink / stab.	
(0,3)	$\begin{bmatrix} -1 & 0 \\ -6 & -3 \end{bmatrix}$	$\begin{matrix} -1 & -3 \\ \begin{pmatrix} -1 \\ 3 \end{pmatrix} & \begin{pmatrix} 0 \\ 1 \end{pmatrix} \end{matrix}$	$\begin{pmatrix} 0 \\ 3 \end{pmatrix} + c_1 e^{-t} \begin{pmatrix} -1 \\ 3 \end{pmatrix} + c_2 e^{-3t} \begin{pmatrix} 0 \\ 1 \end{pmatrix}$	sink / stab.	
(1,1)	$\begin{bmatrix} -1 & -1 \\ -2 & -1 \end{bmatrix}$	$\begin{matrix} -(1+\sqrt{2}) & -1+\sqrt{2} \\ \begin{pmatrix} \sqrt{2} \\ 1 \end{pmatrix} & \begin{pmatrix} -\sqrt{2} \\ 1 \end{pmatrix} \end{matrix}$	$\begin{pmatrix} 1 \\ 1 \end{pmatrix} + c_1 e^{-(1+\sqrt{2})t} \begin{pmatrix} \sqrt{2} \\ 1 \end{pmatrix} + c_2 e^{-(\sqrt{2}-1)t} \begin{pmatrix} -\sqrt{2} \\ 1 \end{pmatrix}$	Saddle	