

Equilibria Exist in Compact Convex Forward-Invariant Sets

<http://mathoverflow.net/questions/68174/equilibria-exist-in-compact-convex-forward-invariant-sets>
<http://gillesgnacadja.wordpress.com/2011/06/18/equilibria-exist-in-compact-convex-forward-invariant-sets>

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Revision A.02 21 June 2011

Theorem. Consider a continuous map $f : \mathbb{R}^n \rightarrow \mathbb{R}^n$ and suppose that the autonomous dynamical system $\dot{x} = f(x)$ has a semiflow $\varphi : \mathbb{R}_{\geq 0} \times \mathbb{R}^n \rightarrow \mathbb{R}^n$. Let $K \subseteq \mathbb{R}^n$. If K is nonempty, compact, convex and forward-invariant, then K contains an equilibrium of the dynamical system, i.e. a zero of the map f .

According to a reliable source, the above theorem is a standard result everyone uses in dynamical systems without proof. I propose a proof in this document. With $\text{Zero}(f)$ denoting the set of zeros of f , the result is that $K \cap \text{Zero}(f) \neq \emptyset$ for any nonempty, compact, convex, forward-invariant $K \subset \mathbb{R}^n$.

The semiflow φ satisfies the following properties.

- The map $\varphi : \mathbb{R}_{\geq 0} \times \mathbb{R}^n \rightarrow \mathbb{R}^n$ is continuous.
- For every $a \in \mathbb{R}^n$, the map $\varphi(-, a) : \mathbb{R}_{\geq 0} \rightarrow \mathbb{R}^n, t \mapsto \varphi(t, a)$ is of class C^1 and is the solution trajectory originating at a , i.e.
 $\varphi(0, a) = a$ and $\forall t \in \mathbb{R}_{\geq 0}, \frac{\partial \varphi}{\partial t}(t, a) = f(\varphi(t, a))$.
- $\forall t, t' \in \mathbb{R}_{\geq 0}, \forall a \in \mathbb{R}^n, \varphi(t + t', a) = \varphi(t', \varphi(t, a))$.

For $a \in \mathbb{R}^n$, we have

$$f(a) = 0 \iff \forall t \in \mathbb{R}_{\geq 0}, \varphi(t, a) = a. \quad (1)$$

24 With $\Phi(t)$ denoting the set of fixed points of $\varphi(t, -)$ for each $t \in \mathbb{R}_{\geq 0}$, Pro-
 25 perty (1) is equivalent to

$$26 \quad \text{Zero}(f) = \bigcap_{t \in \mathbb{R}_{\geq 0}} \Phi(t). \quad (2)$$

27 Because $\varphi(t, -)$ is continuous for each $t \in \mathbb{R}_{\geq 0}$ and $\mathbb{Q}_{\geq 0}$ is dense in $\mathbb{R}_{\geq 0}$, we
 28 also have

$$29 \quad \text{Zero}(f) = \bigcap_{t \in \mathbb{Q}_{\geq 0}} \Phi(t). \quad (3)$$

30 A straightforward inductive reasoning shows that

$$31 \quad \forall t \in \mathbb{R}_{\geq 0}, \forall n \in \mathbb{Z}_{\geq 0}, \Phi(t) \subseteq \Phi(nt). \quad (4)$$

32 It then results that

$$33 \quad \forall t_1, t_2 \in \mathbb{Q}_{\geq 0}, \exists t \in \mathbb{Q}_{\geq 0} : \Phi(t) \subseteq \Phi(t_1) \cap \Phi(t_2). \quad (5)$$

34 Indeed, with $i \in \{1, 2\}$, let $t_i \in \mathbb{Q}_{\geq 0}$, and let $p_i \in \mathbb{Z}_{\geq 0}$ and $q_i \in \mathbb{Z}_{> 0}$ such that
 35 $t_i = p_i/q_i$. Then let $n_1 = p_1q_2$, $n_2 = p_2q_1$, and $t = 1/(q_1q_2)$. We have $t \in \mathbb{Q}_{\geq 0}$,
 36 $n_i \in \mathbb{Z}_{\geq 0}$ and $t_i = n_it$. By Property (4), $\Phi(t) \subseteq \Phi(t_i)$.

37
 38 On another hand, we have

$$39 \quad \forall t \in \mathbb{R}_{\geq 0}, K \cap \Phi(t) \neq \emptyset. \quad (6)$$

40 Indeed, let $t \in \mathbb{R}_{\geq 0}$. Because K is forward-invariant, the (continuous) map
 41 $\varphi(t, -) : \mathbb{R}^n \rightarrow \mathbb{R}^n$ restricts to a continuous map $K \rightarrow K$. And because K is
 42 compact and convex, the Brouwer Fixed Point Theorem implies that $\varphi(t, -)$
 43 has a fixed point in K .

44
 45 Properties (6) and (5) together say that the family $\{K \cap \Phi(t)\}_{t \in \mathbb{Q}_{\geq 0}}$ is a
 46 filter basis and imply that the family has the finite intersection property: for
 47 every finite $T \subset \mathbb{Q}_{\geq 0}$, $\bigcap_{t \in T} (K \cap \Phi(t)) \neq \emptyset$. Furthermore, for every $t \in \mathbb{R}_{\geq 0}$,
 48 $K \cap \Phi(t)$ is a closed subset of K because $\Phi(t)$ is a closed subset of \mathbb{R}^n . Since
 49 K is compact, we have

$$50 \quad \emptyset \neq \bigcap_{t \in \mathbb{Q}_{\geq 0}} (K \cap \Phi(t)) = K \cap \bigcap_{t \in \mathbb{Q}_{\geq 0}} \Phi(t) = K \cap \text{Zero}(f). \quad (7)$$

51 The proof is complete.