Comparing Classical and Nonclassical Symmetries of Nonlinear Partial Differential Equations

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Project Goal

Our research objective for this project was to calculate the classical and nonclassical symmetry groups for the reduced Gibbons-Tsarev equation and the Born-Infeld equation and compare them.

What is a Symmetry?

Definition

A symmetry is a transformation that leaves an object invariant.

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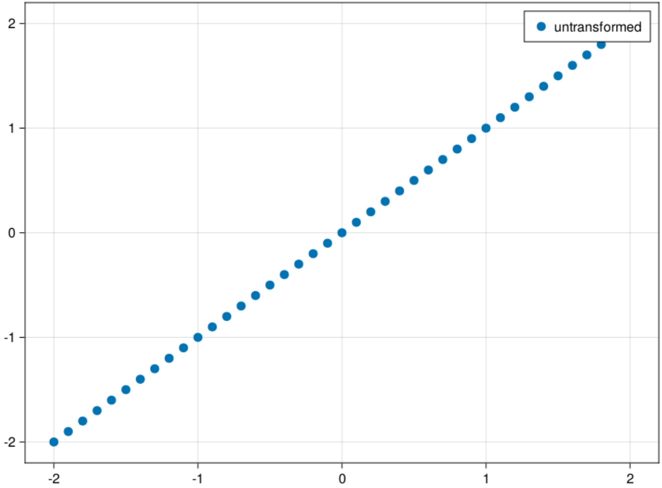
A symmetry is a transformation that leaves an object invariant.

Definition

A symmetry is a change that doesn't change anything.

What is a Symmetry?

Let's see this in action using the simple linear equation $x - y = 0$.



What is a Symmetry?

Example (A Non-Example)

- For our first transformation, let's define new variables $\bar{x} = x + 1$ and $\bar{y} = y$.
- Now we rewrite our equation using these new variables.

$$
\begin{aligned}
\bar{x} - \bar{y} &= 0 && \text{by definition} \\
x + 1 - y &= 0 && \text{by substitution} \\
y &= x + 1 && \text{by rewriting in slope-intercept form}
\end{aligned}
$$

- This transformation is not a symmetry: $x - y + 1 \neq x - y$

What is a Symmetry?

A Transformation that is a Symmetry

Example (2)

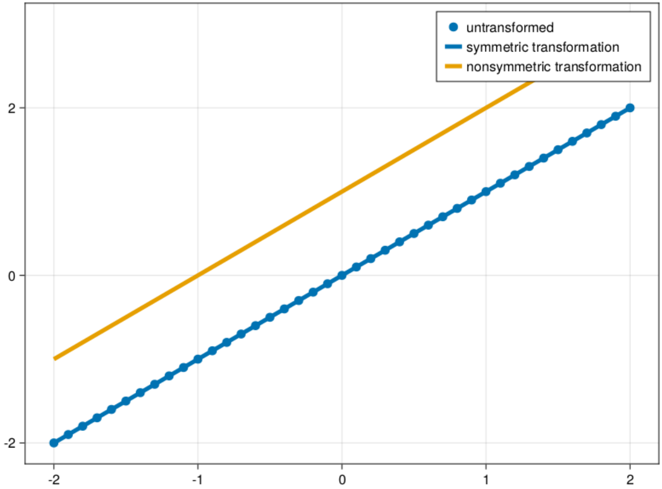
- Let's define some new variables again
  $\bar{x} = x + 1$ and $\bar{y} = y + 1$.
- Now we rewrite our equation using these new variables.

$$
\begin{aligned}
\bar{x} - \bar{y} &= 0 && \text{by definition} \\
(x + 1) - (y + 1) &= 0 && \text{by substitution} \\
(x - y) + (1 - 1) &= 0 && \text{by algebra} \\
x - y &= 0 && \text{by algebra} \\
y &= x && \text{by rewriting in slope-intercept form}
\end{aligned}
$$

- This transformation is a symmetry:
  $x - y = x - y$

What is a Symmetry?

The graphs of our three equations.



What is a Symmetry?

Who cares?

- Symmetries help us understand and solve equations that we wouldn't normally be able to.

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- Symmetries help us understand and solve equations that we wouldn't normally be able to.
- Symmetries encode physically meaningful aspects of equations, like conservation laws.

What is a Differential Equation?

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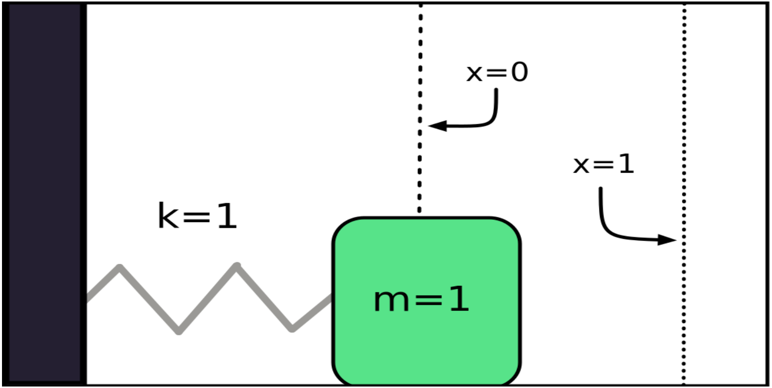
Definition

- A differential equation is an equation that contains both an unknown function and information about how that function relates to its rates of change.
- Differential equations show up everywhere we model something using information about how that thing changes. This includes everything from population dynamics to planetary orbits.
- Differential equations are different from algebraic equations, and can't be solved in the same ways.

What is a Differential Equation?

As an example, let's look a frictionless spring-mass system.



What is a Differential Equation?

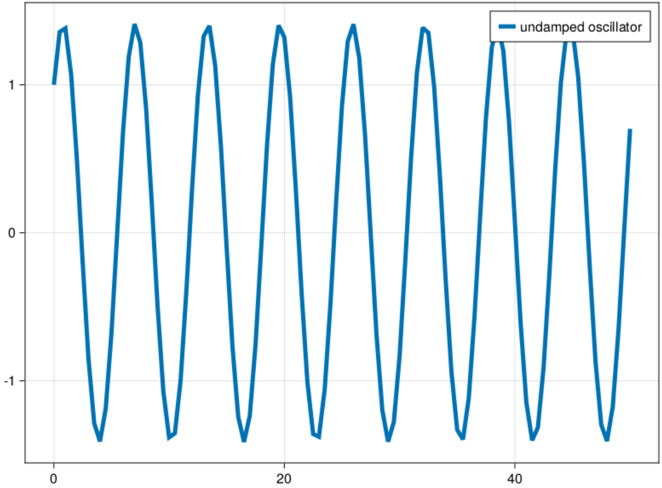
This system can be modeled by the following differential equation.

$$m\ddot{x} = -\kappa x$$

- Here m is the mass, $\ddot{x}$ is the acceleration, κ is the spring constant, and x is the position.
- If we set both m and κ to 1, we get $\ddot{x} = -x$.
- This is a simple differential equation with the algebraic solution of $x(t) = c_1 \cos(t) + c_2 \sin(t)$.

What is a Differential Equation?

The graph of our spring system $x(t) = \cos(t) + \sin(t)$, where $c_1 = c_2 = 1$.



The History of the Born-Infeld and the reduced Gibbons-Tsarev Equations

The Classical Symmetries of the Born-Infeld and the reduced Gibbons-Tsarev Equations

- The goal of our project was to find symmetry transformations for these two PDEs, both classical and nonclassical, and compare them.
- It turns out that there's a standard method for calculating both kinds of symmetry transformations for differential equations.

$$
\begin{aligned}
\text{Input Equation} &\rightarrow \text{Calculate Lie's invariance condition}\\
&\rightarrow \text{Solve linear system of PDEs}\\
&\rightarrow \text{Symmetries!}
\end{aligned}
$$

The Classical Symmetries of the Born-Infeld and the reduced Gibbons-Tsarev Equations

- To guarantee that a transformation is a symmetry, we need to ensure that all aspects of the equation remain the same under the transformation.

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- To guarantee that a transformation is a symmetry, we need to ensure that all aspects of the equation remain the same under the transformation.
- For a differential equation, this means that the function and any derivatives of that function that are present in the equation must not change under the transformation.
- Lie's invariance condition gives us a way to generate transformations that meet all these requirements.
- If you can solve Lie's invariance condition for your equation, you can find its symmetries.

The Classical Symmetries of the Born-Infeld and the reduced Gibbons-Tsarev Equations

The general form of Lie's invariance condition is the falsely unassuming

$$\Gamma^{(n)}\Delta|_{\Delta=0} = 0$$

Here Γ is the infinitesimal operator, n is the order of the equation, and Δ is the equation itself set to equal 0 (this is standard form).

The Classical Symmetries of the Born-Infeld and the reduced Gibbons-Tsarev Equations

For our equations, the infinitesimal operator Γ looks like the following:

$$T\frac{\partial}{\partial t}+X\frac{\partial}{\partial x}+U\frac{\partial}{\partial u}+U_{[t]}\frac{\partial}{\partial u_t}+U_{[x]}\frac{\partial}{\partial u_x}+U_{[tt]}\frac{\partial}{\partial u_{tt}}+U_{[tx]}\frac{\partial}{\partial u_{tx}}+U_{[xx]}\frac{\partial}{\partial u_{xx}}$$

$$\begin{aligned}
U_{[t]} &= D_t(U) - u_t D_t(T) - u_x D_t(X) \\
U_{[x]} &= D_x(U) - u_t D_x(T) - u_x D_x(X) \\
U_{[tt]} &= D_t(U_{[t]}) - u_{tt} D_t(T) - u_{tx} D_t(X) \\
U_{[tx]} &= D_t(U_{[x]}) - u_{tx} D_t(T) - u_{xx} D_t(X) \\
U_{[xx]} &= D_t(U_{[x]}) - u_{tx} D_x(T) - u_{xx} D_x(X)
\end{aligned}$$

$$\begin{aligned}
D_t &= \frac{\partial}{\partial t} + u_t\frac{\partial}{\partial u} + u_{tt}\frac{\partial}{\partial u_t} + u_{tx}\frac{\partial}{\partial u_x} \\
D_x &= \frac{\partial}{\partial x} + u_x\frac{\partial}{\partial u} + u_{tx}\frac{\partial}{\partial u_t} + u_{xx}\frac{\partial}{\partial u_x}
\end{aligned}$$

The Classical Symmetries of the Born-Infeld and the reduced Gibbons-Tsarev Equations

- The result of putting our PDEs through Lie's invariance condition was a system of 24 linear PDEs for the Born-Infeld equation and 21 for the reduced Gibbons-Tsarev equation.

The Classical Symmetries of the Born-Infeld and the reduced Gibbons-Tsarev Equations

- The result of putting our PDEs through Lie's invariance condition was a system of 24 linear PDEs for the Born-Infeld equation and 21 for the reduced Gibbons-Tsarev equation.
- Though difficult, these systems were easier to solve than the original single equations because of their linearity. This resulted in the following symmetries.

The Classical Symmetries of the Born-Infeld and the reduced Gibbons-Tsarev Equations

Classical Symmetries of the Born-Infeld Equation

- $X(x, y, u) = c_1 x + c_2 u + c_3 y + c_4$
- $Y(x, y, u) = c_1 y + c_3 x + c_5 u + c_6$
- $U(x, y, u) = c_1 u - c_2 x + c_5 y + c_7$

Classical Symmetries of the reduced Gibbons-Tsarev Equation

- $X(x, y, u) = -2c_5 y + (-c_2 + 2c_4)x + c_7$
- $Y(x, y, u) = -\frac{c_1 x}{2} + c_4 y + c_5 u + c_6$
- $U(x, y, u) = c_1 y + c_2 u + c_3$

The Nonclassical Symmetries of the Born-Infeld and the reduced Gibbons-Tsarev Equations

Future Work: Does Integrability Imply Equivalence of Classical and Nonclassical Symmetries?

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