# The Rössler System

Steven Rosendahl

■ Created by Otto Rössler in 1976

- Created by Otto Rössler in 1976
- System constructed to display simplest possible Strange Attractor

- Created by Otto Rössler in 1976
- System constructed to display simplest possible Strange Attractor

#### **Definition**

An attractor is a set of values towards which a system moves when initial conditions are *near* the attractor.

- Created by Otto Rössler in 1976
- System constructed to display simplest possible Strange Attractor

#### Definition

An attractor is a set of values towards which a system moves when initial conditions are *near* the attractor. An attractor is called strange if it exhibits fractal behavior.

- Created by Otto Rössler in 1976
- System constructed to display simplest possible Strange Attractor

#### Definition

An attractor is a set of values towards which a system moves when initial conditions are *near* the attractor. An attractor is called strange if it exhibits fractal behavior.

■ Strange attractors are often associated with chaotic systems.

$$\dot{x} = -y - z$$

$$\dot{y} = x + ay$$

$$\dot{z} = b + z(x - c)$$

$$\dot{x} = -y - z$$

$$\dot{y} = x + ay$$

$$\dot{z} = b + z(x - c)$$

a, b, c are responsible for attractive behavior

$$\dot{x} = -y - z$$

$$\dot{y} = x + ay$$

$$\dot{z} = b + z(x - c)$$

- a, b, c are responsible for attractive behavior
- Want to analyze the effect small *a* and *b* have on system

$$\dot{x} = -y - z$$

$$\dot{y} = x + ay$$

$$\dot{z} = b + z(x - c)$$

- a, b, c are responsible for attractive behavior
- Want to analyze the effect small *a* and *b* have on system
  - Is the system globally stable? Locally?

$$\dot{x} = -y - z$$

$$\dot{y} = x + ay$$

$$\dot{z} = b + z(x - c)$$

- a, b, c are responsible for attractive behavior
- Want to analyze the effect small *a* and *b* have on system
  - Is the system globally stable? Locally?
  - When does chaotic behavior occur?

## First Glance

■ Finding fixed points

## First Glance

■ Finding fixed points

Solve[f[x, y, z] == 0 && g[x, y, z] == 0 && h[x, y, z] == 0, 
$$\{x, y, z\}$$
]

## First Glance

### Finding fixed points

Solve[f[x, y, z] == 0 && g[x, y, z] == 0 && h[x, y, z] == 0, 
$$\{x, y, z\}$$
]

$$\begin{cases} x = \frac{1}{2} \left( c - \sqrt{c^2 - 4ab} \right) \\ y = \frac{1}{2} \left( \frac{\sqrt{c^2 - 4ab}}{a} - \frac{c}{a} \right) \\ z = \frac{c - \sqrt{c^2 - 4ab}}{2a} \end{cases}$$

$$\begin{cases} x = \frac{1}{2} \left( c + \sqrt{c^2 - 4ab} \right) \\ y = \frac{1}{2} \left( -\frac{\sqrt{c^2 - 4ab}}{a} - \frac{c}{a} \right) \\ z = \frac{c + \sqrt{c^2 - 4ab}}{2a} \end{cases}$$

■ Let a, b tend to zero

- Let a, b tend to zero
- Cannot actually be zero (division by 0 at fixed points)

- Let a, b tend to zero
- Cannot actually be zero (division by 0 at fixed points)

$$\{x = 0 \quad y = 0 \quad z = 0\}$$

- Let a, b tend to zero
- Cannot actually be zero (division by 0 at fixed points)

$$\{x = 0 \quad y = 0 \quad z = 0\}$$

$$\left\{ x = c \qquad y = -\frac{c}{a} \qquad z = \frac{c}{a} \right\}$$

- Let a, b tend to zero
- Cannot actually be zero (division by 0 at fixed points)

$$\{x = 0 \quad y = 0 \quad z = 0\}$$

$$\left\{ x = c \qquad y = -\frac{c}{a} \qquad z = \frac{c}{a} \right\}$$

Much easier to analyze stability of system

Can take Jacobian of system to analyze stability

- Can take Jacobian of system to analyze stability
- Which stabilities are hyperbolic in a 3D system?

- Can take Jacobian of system to analyze stability
- Which stabilities are hyperbolic in a 3D system?

#### Definition

When  $\lambda_1 \in \mathbb{R}$  and  $\lambda_2, \lambda_3$  are complex conjugates and the real part of  $\lambda_1, \lambda_2$ , and  $\lambda_3$  all have the same sign, the fixed point is called a Focus Node

- Can take Jacobian of system to analyze stability
- Which stabilities are hyperbolic in a 3D system?

#### Definition

When  $\lambda_1 \in \mathbb{R}$  and  $\lambda_2, \lambda_3$  are complex conjugates and the real part of  $\lambda_1, \lambda_2$ , and  $\lambda_3$  all have the same sign, the fixed point is called a Focus Node

#### Definition

When  $\lambda_1 \in \mathbb{R}$  and  $\lambda_2, \lambda_3$  are complex conjugates, then if the sign of  $\lambda_1$  is the opposite of the sign of the real part of  $\lambda_2$  and  $\lambda_3$ , the fixed point is called a Saddle Focus

- Can take Jacobian of system to analyze stability
- Which stabilities are hyperbolic in a 3D system?

#### Definition

When  $\lambda_1 \in \mathbb{R}$  and  $\lambda_2, \lambda_3$  are complex conjugates and the real part of  $\lambda_1, \lambda_2$ , and  $\lambda_3$  all have the same sign, the fixed point is called a Focus Node

#### Definition

When  $\lambda_1 \in \mathbb{R}$  and  $\lambda_2, \lambda_3$  are complex conjugates, then if the sign of  $\lambda_1$  is the opposite of the sign of the real part of  $\lambda_2$  and  $\lambda_3$ , the fixed point is called a Saddle Focus

 Other stability exists, but are often named after the bifurcations that produce them



Jacobian of system will tell us about behavior of fixed points

Jacobian of system will tell us about behavior of fixed points

$$|J(0,0,0) - \lambda I| = \begin{vmatrix} -\lambda & -1 & -1 \\ 1 & -\lambda & 0 \\ 0 & 0 & -c - \lambda \end{vmatrix} = (c - \lambda)(\lambda + 1)^2 = 0.$$

Jacobian of system will tell us about behavior of fixed points

$$|J(0,0,0) - \lambda I| = \begin{vmatrix} -\lambda & -1 & -1 \\ 1 & -\lambda & 0 \\ 0 & 0 & -c - \lambda \end{vmatrix} = (c - \lambda)(\lambda + 1)^2 = 0.$$

Jacobian of system will tell us about behavior of fixed points

$$|J(0,0,0) - \lambda I| = \begin{vmatrix} -\lambda & -1 & -1 \\ 1 & -\lambda & 0 \\ 0 & 0 & -c - \lambda \end{vmatrix} = (c - \lambda)(\lambda + 1)^2 = 0.$$

$$\lambda = -i$$

Jacobian of system will tell us about behavior of fixed points

$$|J(0,0,0) - \lambda I| = \begin{vmatrix} -\lambda & -1 & -1 \\ 1 & -\lambda & 0 \\ 0 & 0 & -c - \lambda \end{vmatrix} = (c - \lambda)(\lambda + 1)^2 = 0.$$

$$\lambda = -i$$
  $\lambda = i$ 

Jacobian of system will tell us about behavior of fixed points

$$|J(0,0,0) - \lambda I| = \begin{vmatrix} -\lambda & -1 & -1 \\ 1 & -\lambda & 0 \\ 0 & 0 & -c - \lambda \end{vmatrix} = (c - \lambda)(\lambda + 1)^2 = 0.$$

$$\lambda = -i$$
  $\lambda = i$   $\lambda = -c$ 



Jacobian of system will tell us about behavior of fixed points

$$|J(0,0,0) - \lambda I| = \begin{vmatrix} -\lambda & -1 & -1 \\ 1 & -\lambda & 0 \\ 0 & 0 & -c - \lambda \end{vmatrix} = (c - \lambda)(\lambda + 1)^2 = 0.$$

System has three eigenvalues

$$\lambda = -i$$
  $\lambda = i$   $\lambda = -c$ 

#### Definition

If two of the eigenvalues of the system are pure imaginary, then the system has a center at the fixed point. This is **not** a hyperbolic equilibrium.

Jacobian of system will tell us about behavior of fixed points

$$|J(0,0,0) - \lambda I| = \begin{vmatrix} -\lambda & -1 & -1 \\ 1 & -\lambda & 0 \\ 0 & 0 & -c - \lambda \end{vmatrix} = (c - \lambda)(\lambda + 1)^2 = 0.$$

System has three eigenvalues

$$\lambda = -i$$
  $\lambda = i$   $\lambda = -c$ 

#### Definition

If two of the eigenvalues of the system are pure imaginary, then the system has a **center** at the fixed point. This is **not** a hyperbolic equilibrium.

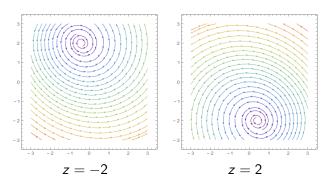
 $\blacksquare$   $\therefore$  (0,0,0) is a center of the linear system



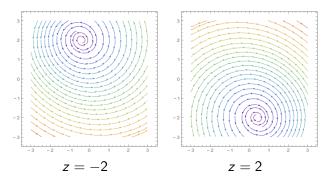
■ How to analyze the center of linear system?

- How to analyze the center of linear system?
- Hold z constant

- How to analyze the center of linear system?
- Hold z constant
- Look at behavior of (0,0) in x-y plane



- How to analyze the center of linear system?
- Hold z constant
- Look at behavior of (0,0) in x-y plane



Actually appears to be a spiral



$$\left|J\left(c,-\frac{c}{a},\frac{c}{a}\right)-\lambda I\right|=\frac{ac-a\lambda-c\lambda+a^2\lambda^2-a\lambda^3}{a}.$$

Can analyze the other fixed point

$$\left|J\left(c,-\frac{c}{a},\frac{c}{a}\right)-\lambda I\right|=\frac{ac-a\lambda-c\lambda+a^2\lambda^2-a\lambda^3}{a}.$$

Solving with Mathematica yields bad values

$$\left|J\left(c,-\frac{c}{a},\frac{c}{a}\right)-\lambda I\right|=\frac{ac-a\lambda-c\lambda+a^2\lambda^2-a\lambda^3}{a}.$$

- Solving with Mathematica yields bad values
- Recall system was meant to be analyzed with small a, b

$$\left|J\left(c,-\frac{c}{a},\frac{c}{a}\right)-\lambda I\right|=\frac{ac-a\lambda-c\lambda+a^2\lambda^2-a\lambda^3}{a}.$$

- Solving with Mathematica yields bad values
- Recall system was meant to be analyzed with small a, b
- Let  $a \rightarrow 0.14$ ,  $c \rightarrow 8.8$

$$\left|J\left(c,-\frac{c}{a},\frac{c}{a}\right)-\lambda I\right|=\frac{ac-a\lambda-c\lambda+a^2\lambda^2-a\lambda^3}{a}.$$

- Solving with Mathematica yields bad values
- Recall system was meant to be analyzed with small a, b
- Let  $a \to 0.14$ ,  $c \to 8.8$  $\lambda = 0.001 - 7.99i$

$$\left|J\left(c,-\frac{c}{a},\frac{c}{a}\right)-\lambda I\right|=\frac{ac-a\lambda-c\lambda+a^2\lambda^2-a\lambda^3}{a}.$$

- Solving with Mathematica yields bad values
- Recall system was meant to be analyzed with small a, b
- Let  $a \to 0.14$ ,  $c \to 8.8$  $\lambda = 0.001 - 7.99i$   $\lambda = 0.001 + 7.99i$

$$\left|J\left(c,-\frac{c}{a},\frac{c}{a}\right)-\lambda I\right|=\frac{ac-a\lambda-c\lambda+a^2\lambda^2-a\lambda^3}{a}.$$

- Solving with Mathematica yields bad values
- Recall system was meant to be analyzed with small a, b
- Let a o 0.14, c o 8.8  $\lambda = 0.001 7.99i$   $\lambda = 0.001 + 7.99i$   $\lambda = 0.13$

$$\left|J\left(c,-\frac{c}{a},\frac{c}{a}\right)-\lambda I\right|=\frac{ac-a\lambda-c\lambda+a^2\lambda^2-a\lambda^3}{a}.$$

- Solving with Mathematica yields bad values
- Recall system was meant to be analyzed with small a, b
- Let a o 0.14, c o 8.8  $\lambda = 0.001 7.99i$   $\lambda = 0.001 + 7.99i$   $\lambda = 0.13$
- ∴ fixed point is an unstable focus node

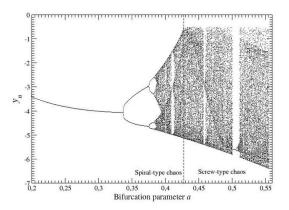




Mathematica demonstration

Rössler bifurcations display chaotic behavior

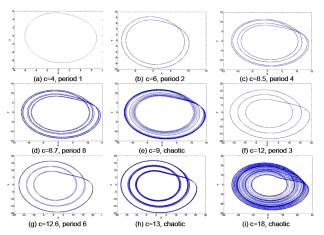
Rössler bifurcations display chaotic behavior



■ Small changes in the system yield drastic changes in behavior

- Small changes in the system yield drastic changes in behavior
- Periodicity changes to chaotic behavior

- Small changes in the system yield drastic changes in behavior
- Periodicity changes to chaotic behavior



### References

- Housam Binous.

  Bifurcation diagram for the rssler attractor.
- Daniel de Souza Carvalho and Eric W. Weisstein.
  The rossler attractor.
- Eugene M. Izhikevich. Equilibrium, 2007.
- Christophe Letellier and Otto E. Rossler. Rossler attractor, 2007.