

## Functional Differential Equations with Causal Operators

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**Abstract:** The aim of this paper is to established the existence of solutions and some properties of set solutions for a class of functional differential equation with causal operator under assumption that the equation satisfies the Carathéodory type condition.

**Keywords:** functional differential equation; causal operator; existence results

### 1 Introduction

The study of differential equations with causal operators has a rapid development in the last years and some results are assembled in a recent monograph [1]. The term of causal operators is adopted from engineering literature and the theory these operators has the powerful quality of unifying ordinary differential equations, integro - differential equations, differential equations with finite or infinite delay, Volterra integral equations, and neutral functional equations, to name a few.

In the paper [6] is considered the class  $\mathcal{S}$  of all infinite - dimensional nonlinear  $M$ - input  $u$ ,  $M$ - output  $y$  systems  $(\rho, f, g, Q)$  given by the following controlled nonlinear functional equation

$$\begin{cases} y'(t) = f(p(t), (\hat{Q}y)(t)) + g(p(t), (\hat{Q}y)(t), u(t)) \\ y|_{[-\sigma, 0]} = y^0 \in C([-\sigma, 0], \mathbb{R}^M) \end{cases} \quad (1)$$

where  $\sigma \geq 0$  quantifies the memory of the system,  $p$  is a perturbation term, and  $\hat{Q}$  is a nonlinear causal operator. The aim of the control objective is the development of a adaptive servomechanism which ensures practical tracking, by the system output, of an arbitrary reference signal assumed to be in the class  $\mathcal{R}$  of all locally absolutely continuous and bounded with essentially bounded derivative.

More exactly, the control objective is to determine an  $(\mathcal{R}, \mathcal{S})$ - servomechanism, that is, to determine the continuous functions  $\Phi : \mathbb{R}^{M+1} \rightarrow \mathbb{R}^{M+1}$  and  $\psi_\lambda : \mathbb{R}_+ \rightarrow \mathbb{R}_+$  (parametrized by  $\lambda > 0$ ) such that, for every system of class  $\mathcal{S}$  and every reference signal  $r \in \mathcal{R}$ , the control

$$u(t) = -k(t)\Phi(y(t) - r(t)), \quad k(t) = \psi_\lambda(\|y(t) - r(t)\|), \quad k|_{[-\sigma, 0]} = k^0, \quad (2)$$

applied to (1) ensures convergence of controller gain and tracking of  $r(\cdot)$  with asymptotic accuracy quantified by  $\lambda > 0$ , in the sense that  $\max\{\|y(t) - r(t)\| - \lambda, 0\} \rightarrow 0$  as  $t \rightarrow \infty$ . For more details (see [6, 10]).

Using (2), we can write (1) as

$$x'(t) = F(t, (Qx)(t)), \quad x|_{[-\sigma, 0]} = x^0 \in C([-\sigma, 0], \mathbb{R}^N), \quad (3)$$

where  $N = M + 1$ ,  $x(t) := (y(t), k(t))$ ,  $x^0 = (y^0, k^0)$ , and  $Q$  is an operator defined on  $C([-\sigma, 0], \mathbb{R}^N)$  by

$$(Qx)(t) = (Q(y, k))(t) := ((\hat{Q}y)(t), y(t), k(t)).$$

The purpose of this article is to study the topological properties of the initial value problem (3). For this we will use ideas from papers [4], [5]. Also, we give an existence result for this problem, assuming only the continuity of the operator  $Q$ . In the paper [6] is also obtained an existence result assuming that the operator  $Q$  is a locally Lipschitz operator.

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# Functional Differential Operators And Equations

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