

Dynamics of nematic liquid crystal systems: The quasilinear approach

Katharina Schade, TU Darmstadt



joint work with M. Hieber, M. Nesensohn and J. Prüss



8th Japanese-German International Workshop on
Mathematical Fluid Dynamics

Waseda University,
June 19, 2013

1. The model

- Ω : bounded C^2 domain

$$(LCD) \left\{ \begin{array}{lcl} \partial_t u + (u \cdot \nabla) u - \Delta u + \nabla \pi & = & -\operatorname{div}([\nabla d]^\top \nabla d) \\ \partial_t d + (u \cdot \nabla) d & = & \Delta d + |\nabla d|^2 d \\ |d| & = & 1 \\ \operatorname{div} u & = & 0 \\ (u, \partial_\nu d) & = & (0, 0) \\ (u, d)|_{t=0} & = & (u_0, d_0) \end{array} \right. \begin{array}{l} \text{in } (0, T) \times \Omega, \\ \text{on } (0, T) \times \partial\Omega, \\ \text{in } \Omega. \end{array}$$

$u : (0, \infty) \times \Omega \rightarrow \mathbb{R}^n$: velocity,

$\pi : (0, \infty) \times \Omega \rightarrow \mathbb{R}$: pressure,

$d : (0, \infty) \times \Omega \rightarrow \mathbb{R}^n$: macroscopic orientation of a molecule.

1. The model

- Ω : bounded C^2 domain

$$(LCD) \left\{ \begin{array}{lcl} \partial_t u + (u \cdot \nabla) u - \Delta u + \nabla \pi & = & -\operatorname{div}([\nabla d]^\top \nabla d) \\ \partial_t d + (u \cdot \nabla) d & = & \Delta d + |\nabla d|^2 d \\ |d| & = & 1 \\ \operatorname{div} u & = & 0 \\ (u, \partial_\nu d) & = & (0, 0) \\ (u, d)|_{t=0} & = & (u_0, d_0) \end{array} \right. \begin{array}{l} \text{in } (0, T) \times \Omega, \\ \text{on } (0, T) \times \partial\Omega, \\ \text{in } \Omega. \end{array}$$

$u : (0, \infty) \times \Omega \rightarrow \mathbb{R}^n$: velocity,

$\pi : (0, \infty) \times \Omega \rightarrow \mathbb{R}$: pressure,

$d : (0, \infty) \times \Omega \rightarrow \mathbb{R}^n$: macroscopic orientation of a molecule.

1. The model

- Ω : bounded C^2 domain

$$(LCD) \left\{ \begin{array}{lcl} \partial_t u + (u \cdot \nabla) u - \Delta u + \nabla \pi & = & -\operatorname{div}([\nabla d]^T \nabla d) \\ \partial_t d + (u \cdot \nabla) d & = & \Delta d + |\nabla d|^2 d \\ |d| & = & 1 \\ \operatorname{div} u & = & 0 \\ (u, \partial_\nu d) & = & (0, 0) \\ (u, d)|_{t=0} & = & (u_0, d_0) \end{array} \right. \begin{array}{l} \text{in } (0, T) \times \Omega, \\ \text{on } (0, T) \times \partial\Omega, \\ \text{in } \Omega. \end{array}$$

$u : (0, \infty) \times \Omega \rightarrow \mathbb{R}^n$: velocity,

$\pi : (0, \infty) \times \Omega \rightarrow \mathbb{R}$: pressure,

$d : (0, \infty) \times \Omega \rightarrow \mathbb{R}^n$: macroscopic orientation of a molecule.

1. The model

- Ω : bounded C^2 domain

$$(LCD) \left\{ \begin{array}{lcl} \partial_t u + (u \cdot \nabla) u - \Delta u + \nabla \pi & = & -\operatorname{div}([\nabla d]^\top \nabla d) \\ \partial_t d + (u \cdot \nabla) d & = & \Delta d + |\nabla d|^2 d \\ |d| & = & 1 \\ \operatorname{div} u & = & 0 \\ (u, \partial_\nu d) & = & (0, 0) \\ (u, d)|_{t=0} & = & (u_0, d_0) \end{array} \right. \begin{array}{l} \text{in } (0, T) \times \Omega, \\ \text{on } (0, T) \times \partial\Omega, \\ \text{in } \Omega. \end{array}$$

$u : (0, \infty) \times \Omega \rightarrow \mathbb{R}^n$: velocity,

$\pi : (0, \infty) \times \Omega \rightarrow \mathbb{R}$: pressure,

$d : (0, \infty) \times \Omega \rightarrow \mathbb{R}^n$: macroscopic orientation of a molecule.

1. The model

- Ω : bounded C^2 domain

$$(LCD) \left\{ \begin{array}{lcl} \partial_t u + (u \cdot \nabla) u - \Delta u + \nabla \pi & = & -\operatorname{div}([\nabla d]^\top \nabla d) \\ \partial_t d + (u \cdot \nabla) d & = & \Delta d + |\nabla d|^2 d \\ |d| & = & 1 \\ \operatorname{div} u & = & 0 \\ (u, \partial_\nu d) & = & (0, 0) \\ (u, d)|_{t=0} & = & (u_0, d_0) \end{array} \right. \begin{array}{l} \text{in } (0, T) \times \Omega, \\ \text{on } (0, T) \times \partial\Omega, \\ \text{in } \Omega. \end{array}$$

$u : (0, \infty) \times \Omega \rightarrow \mathbb{R}^n$: velocity,

$\pi : (0, \infty) \times \Omega \rightarrow \mathbb{R}$: pressure,

$d : (0, \infty) \times \Omega \rightarrow \mathbb{R}^n$: macroscopic orientation of a molecule.

2. (LCD) as quasilinear problem?

$$(LCD) \quad \begin{cases} \partial_t u + (u \cdot \nabla) u - \Delta u + \nabla \pi = -\operatorname{div}([\nabla d]^T \nabla d) & \text{in } (0, T) \times \Omega, \\ \partial_t d + (u \cdot \nabla) d = \Delta d + |\nabla d|^2 d & \text{in } (0, T) \times \Omega. \end{cases}$$

$$(QL) \quad \partial_t z + \mathcal{A}(z(t))z = F(z(t)).$$

2. (LCD) as quasilinear problem?

$$(LCD) \quad \left\{ \begin{array}{lcl} \partial_t u + \mathbb{P}(u \cdot \nabla) u - \mathbb{P}\Delta u & = & -\mathbb{P}\text{div}([\nabla d]^\top \nabla d) \quad \text{in } (0, T) \times \Omega, \\ \partial_t d + (u \cdot \nabla) d & = & \Delta d + |\nabla d|^2 d \quad \text{in } (0, T) \times \Omega. \end{array} \right.$$

$$(QL) \quad \partial_t z + \mathcal{A}(z(t))z = F(z(t)).$$

- ▶ \mathbb{P} : Helmholtz projection.

2. (LCD) as quasilinear problem?

$$(LCD) \quad \begin{cases} \partial_t \mathbf{u} + \mathbb{P}(\mathbf{u} \cdot \nabla) \mathbf{u} - \mathbb{P} \Delta \mathbf{u} &= -\mathbb{P} \operatorname{div}([\nabla d]^T \nabla d) & \text{in } (0, T) \times \Omega, \\ \partial_t d + (\mathbf{u} \cdot \nabla) d &= \Delta d + |\nabla d|^2 d & \text{in } (0, T) \times \Omega. \end{cases}$$

$$(QL) \quad \partial_t z + \mathcal{A}(z(t))z = F(z(t)).$$

- \mathbb{P} : Helmholtz projection.

2. (LCD) as quasilinear problem?

$$(LCD) \quad \begin{cases} \partial_t u + \mathbb{P}(u \cdot \nabla) u - \mathbb{P} \Delta u &= -\mathbb{P} \operatorname{div}([\nabla d]^T \nabla d) \quad \text{in } (0, T) \times \Omega, \\ \partial_t d + (u \cdot \nabla) d &= \Delta d + |\nabla d|^2 d \quad \text{in } (0, T) \times \Omega. \end{cases}$$

$$(QL) \quad \partial_t \begin{pmatrix} u \\ d \end{pmatrix} + \mathcal{A}(z(t)) z = F(z(t)).$$

- ▶ \mathbb{P} : Helmholtz projection.

2. (LCD) as quasilinear problem?

$$(LCD) \quad \begin{cases} \partial_t u + \mathbb{P}(u \cdot \nabla) u - \mathbb{P}\Delta u &= -\mathbb{P}\operatorname{div}([\nabla d]^\top \nabla d) \quad \text{in } (0, T) \times \Omega, \\ \partial_t d + (u \cdot \nabla) d &= \Delta d + |\nabla d|^2 d \quad \text{in } (0, T) \times \Omega. \end{cases}$$

$$(QL) \quad \partial_t \begin{pmatrix} u \\ d \end{pmatrix} + \mathcal{A}(z(t)) z = F(z(t)).$$

- ▶ \mathbb{P} : Helmholtz projection.

2. (LCD) as quasilinear problem?

$$(LCD) \quad \begin{cases} \partial_t u + \mathbb{P}(u \cdot \nabla) u - \mathbb{P} \Delta u &= -\mathbb{P} \operatorname{div}([\nabla d]^T \nabla d) \quad \text{in } (0, T) \times \Omega, \\ \partial_t d + (u \cdot \nabla) d &= \Delta d + |\nabla d|^2 d \quad \text{in } (0, T) \times \Omega. \end{cases}$$

$$(QL) \quad \partial_t \begin{pmatrix} u \\ d \end{pmatrix} + \begin{bmatrix} -A_q & \\ & \end{bmatrix} \begin{pmatrix} u \\ d \end{pmatrix} = F(z(t)).$$

- ▶ \mathbb{P} : Helmholtz projection.
- ▶ A_q : Stokes Operator

2. (LCD) as quasilinear problem?

$$(LCD) \quad \begin{cases} \partial_t u + \mathbb{P}(u \cdot \nabla) u - \mathbb{P} \Delta u &= -\mathbb{P} \operatorname{div}([\nabla d]^T \nabla d) \quad \text{in } (0, T) \times \Omega, \\ \partial_t d + (u \cdot \nabla) d &= \Delta d + |\nabla d|^2 d \quad \text{in } (0, T) \times \Omega. \end{cases}$$

$$(QL) \quad \partial_t \begin{pmatrix} u \\ d \end{pmatrix} + \begin{bmatrix} -A_q & \\ & \end{bmatrix} \begin{pmatrix} u \\ d \end{pmatrix} = F(z(t)).$$

- ▶ \mathbb{P} : Helmholtz projection.
- ▶ A_q : Stokes Operator

2. (LCD) as quasilinear problem?

$$(LCD) \quad \left\{ \begin{array}{lcl} \partial_t u + \mathbb{P}(u \cdot \nabla) u - \mathbb{P} \Delta u & = & -\mathbb{P} \operatorname{div}([\nabla d]^T \nabla d) \quad \text{in } (0, T) \times \Omega, \\ \partial_t d + (u \cdot \nabla) d & = & \Delta d + |\nabla d|^2 d \quad \text{in } (0, T) \times \Omega. \end{array} \right.$$

$$(QL) \quad \partial_t \begin{pmatrix} u \\ d \end{pmatrix} + \begin{bmatrix} -A_q & \\ & -\Delta_q^N \end{bmatrix} \begin{pmatrix} u \\ d \end{pmatrix} = F(z(t)).$$

- ▶ \mathbb{P} : Helmholtz projection.
- ▶ A_q : Stokes Operator , Δ_q^N : Neumann-Laplace Operator.

2. (LCD) as quasilinear problem?

$$(LCD) \quad \begin{cases} \partial_t u + \mathbb{P}(u \cdot \nabla) u - \mathbb{P} \Delta u &= -\mathbb{P} \operatorname{div}([\nabla d]^T \nabla d) & \text{in } (0, T) \times \Omega, \\ \partial_t d + (u \cdot \nabla) d &= \Delta d + |\nabla d|^2 d & \text{in } (0, T) \times \Omega. \end{cases}$$

$$(QL) \quad \partial_t \begin{pmatrix} u \\ d \end{pmatrix} + \begin{bmatrix} -A_q & \\ & -\Delta_q^N \end{bmatrix} \begin{pmatrix} u \\ d \end{pmatrix} = F(z(t)).$$

- ▶ \mathbb{P} : Helmholtz projection.
- ▶ A_q : Stokes Operator , Δ_q^N : Neumann-Laplace Operator.

2. (LCD) as quasilinear problem?

$$(LCD) \quad \begin{cases} \partial_t u + \mathbb{P}(u \cdot \nabla) u - \mathbb{P} \Delta u &= -\mathbb{P} \operatorname{div}([\nabla d]^\top \nabla d) & \text{in } (0, T) \times \Omega, \\ \partial_t d + (u \cdot \nabla) d &= \Delta d + |\nabla d|^2 d & \text{in } (0, T) \times \Omega. \end{cases}$$

$$(QL) \quad \partial_t \begin{pmatrix} u \\ d \end{pmatrix} + \begin{bmatrix} -A_q & \mathbb{P} \mathcal{B}_q(d) \\ & -\Delta_q^N \end{bmatrix} \begin{pmatrix} u \\ d \end{pmatrix} = F(z(t)).$$

- ▶ \mathbb{P} : Helmholtz projection.
- ▶ A_q : Stokes Operator , Δ_q^N : Neumann-Laplace Operator.
- ▶ Bilinearform $[\mathcal{B}_q(d)h]_i := \partial_i d_l \Delta h_l + \partial_k d_l \partial_k \partial_i h_l$, i. e. $\mathcal{B}(d)(d) = \operatorname{div}([\nabla d]^\top \nabla d)$.

2. (LCD) as quasilinear problem?

$$(LCD) \quad \begin{cases} \partial_t u + \mathbb{P}(u \cdot \nabla) u - \mathbb{P} \Delta u &= -\mathbb{P} \operatorname{div}([\nabla d]^T \nabla d) & \text{in } (0, T) \times \Omega, \\ \partial_t d + (u \cdot \nabla) d &= \Delta d + |\nabla d|^2 d & \text{in } (0, T) \times \Omega. \end{cases}$$

$$(QL) \quad \partial_t \begin{pmatrix} u \\ d \end{pmatrix} + \begin{bmatrix} -A_q & \mathbb{P}\mathcal{B}_q(d) \\ & -\Delta_q^N \end{bmatrix} \begin{pmatrix} u \\ d \end{pmatrix} = F(z(t)).$$

- ▶ \mathbb{P} : Helmholtz projection.
- ▶ A_q : Stokes Operator , Δ_q^N : Neumann-Laplace Operator.
- ▶ Bilinearform $[\mathcal{B}_q(d)h]_i := \partial_i d_l \Delta h_l + \partial_k d_l \partial_k \partial_i h_l$, i. e. $\mathcal{B}(d)(d) = \operatorname{div}([\nabla d]^T \nabla d)$.

2. (LCD) as quasilinear problem?

$$(LCD) \quad \begin{cases} \partial_t u + \mathbb{P}(u \cdot \nabla) u - \mathbb{P} \Delta u &= -\mathbb{P} \operatorname{div}([\nabla d]^\top \nabla d) & \text{in } (0, T) \times \Omega, \\ \partial_t d + (u \cdot \nabla) d &= \Delta d + |\nabla d|^2 d & \text{in } (0, T) \times \Omega. \end{cases}$$
$$(QL) \quad \partial_t \begin{pmatrix} u \\ d \end{pmatrix} + \begin{bmatrix} -A_q & \mathbb{P}\mathcal{B}_q(d) \\ 0 & -\Delta_q^N \end{bmatrix} \begin{pmatrix} u \\ d \end{pmatrix} = \begin{pmatrix} -\mathbb{P}u \cdot \nabla u \\ -u \cdot \nabla d + |\nabla d|^2 d \end{pmatrix}.$$

- ▶ \mathbb{P} : Helmholtz projection.
- ▶ A_q : Stokes Operator , Δ_q^N : Neumann-Laplace Operator.
- ▶ Bilinearform $[\mathcal{B}_q(d)h]_i := \partial_i d_l \Delta h_l + \partial_k d_l \partial_k \partial_i h_l$, i. e. $\mathcal{B}(d)(d) = \operatorname{div}([\nabla d]^\top \nabla d)$.

2. (LCD) as quasilinear problem?

$$(LCD) \quad \begin{cases} \partial_t u + \mathbb{P}(u \cdot \nabla) u - \mathbb{P} \Delta u &= -\mathbb{P} \operatorname{div}([\nabla d]^T \nabla d) & \text{in } (0, T) \times \Omega, \\ \partial_t d + (u \cdot \nabla) d &= \Delta d + |\nabla d|^2 d & \text{in } (0, T) \times \Omega. \end{cases}$$
$$(QL) \quad \partial_t \begin{pmatrix} u \\ d \end{pmatrix} + \begin{bmatrix} -A_q & \mathbb{P}\mathcal{B}_q(d) \\ 0 & -\Delta_q^N \end{bmatrix} \begin{pmatrix} u \\ d \end{pmatrix} = \begin{pmatrix} -\mathbb{P}u \cdot \nabla u \\ -u \cdot \nabla d + |\nabla d|^2 d \end{pmatrix}.$$

- ▶ \mathbb{P} : Helmholtz projection.
- ▶ A_q : Stokes Operator , Δ_q^N : Neumann-Laplace Operator.
- ▶ Bilinearform $[\mathcal{B}_q(d)h]_i := \partial_i d_l \Delta h_l + \partial_k d_l \partial_k \partial_i h_l$, i. e. $\mathcal{B}(d)(d) = \operatorname{div}([\nabla d]^T \nabla d)$.
- ▶ Corresponding spaces: ($p, q \in [1, \infty)$ large enough, i.e. $2/p + n/q < 1$)

$$X_0 := L_{q,\sigma}(\Omega) \times L_q(\Omega), \quad X_1 := D(A_q) \times D(D_q),$$

$$X_\gamma := (X_0, X_1)_{1-1/p,p} = B_{q,p}^{2-2/p}(\Omega) + \text{compatibility conditions.}$$

2. (LCD) as quasilinear problem?

$$(LCD) \quad \begin{cases} \partial_t u + \mathbb{P}(u \cdot \nabla) u - \mathbb{P} \Delta u &= -\mathbb{P} \operatorname{div}([\nabla d]^\top \nabla d) & \text{in } (0, T) \times \Omega, \\ \partial_t d + (u \cdot \nabla) d &= \Delta d + |\nabla d|^2 d & \text{in } (0, T) \times \Omega. \end{cases}$$
$$(QL) \quad \partial_t \begin{pmatrix} u \\ d \end{pmatrix} + \begin{bmatrix} -A_q & \mathbb{P}\mathcal{B}_q(d) \\ 0 & -\Delta_q^N \end{bmatrix} \begin{pmatrix} u \\ d \end{pmatrix} = \begin{pmatrix} -\mathbb{P}u \cdot \nabla u \\ -u \cdot \nabla d + |\nabla d|^2 d \end{pmatrix}.$$

- ▶ \mathbb{P} : Helmholtz projection.
- ▶ A_q : Stokes Operator , Δ_q^N : Neumann-Laplace Operator.
- ▶ Bilinearform $[\mathcal{B}_q(d)h]_i := \partial_i d_l \Delta h_l + \partial_k d_l \partial_k \partial_i h_l$, i. e. $\mathcal{B}(d)(d) = \operatorname{div}([\nabla d]^\top \nabla d)$.
- ▶ Corresponding spaces: ($p, q \in [1, \infty)$ large enough, i.e. $2/p + n/q < 1$)

$$X_0 := L_{q,\sigma}(\Omega) \times L_q(\Omega), \quad X_1 := D(A_q) \times D(D_q),$$

$$X_\gamma := (X_0, X_1)_{1-1/p,p} = B_{q,p}^{2-2/p}(\Omega) + \text{compatibility conditions.}$$

- ▶ Problem: $|d| = 1$

3. Existence of local solutions

Theorem

Under suitable initial conditions, it holds

- ▶ *local in time existence and uniqueness of solutions for (QL) in*

$$H_p^1(J; X_0) \cap L_p(J; X_1), \quad J = [0, a],$$

which regularizes instantly in time,

- ▶ *continuous dependence on the data,*
- ▶ *existence of maximal time interval.*

3. Existence of local solutions

Theorem

Under suitable initial conditions, it holds

- ▶ *local in time existence and uniqueness of solutions for (QL) in*

$$H_p^1(J; X_0) \cap L_p(J; X_1), \quad J = [0, a],$$

which regularizes instantly in time,

- ▶ *continuous dependence on the data,*
- ▶ *existence of maximal time interval.*

Idea

- ▶ Exploit tri-diagonal structure of operator matrix $\begin{bmatrix} A_q & \mathbb{P}\mathcal{B}_q(d) \\ 0 & \Delta_q^N \end{bmatrix}$ to obtain maximal regularity

3. Existence of local solutions

Theorem

Under suitable initial conditions, it holds

- ▶ *local in time existence and uniqueness of solutions for (QL) in*

$$H_p^1(J; X_0) \cap L_p(J; X_1), \quad J = [0, a],$$

which regularizes instantly in time,

- ▶ *continuous dependence on the data,*
- ▶ *existence of maximal time interval.*

Idea

- ▶ Exploit tri-diagonal structure of operator matrix $\begin{bmatrix} A_q & \mathbb{P}\mathcal{B}_q(d) \\ 0 & \Delta_q^N \end{bmatrix}$ to obtain maximal regularity
- ▶ Apply abstract result à la Clément and Li + Angenent's trick for smoothing effect

4. $|d| = 1$ is preserved

Condition $|d| = 1$ preserved, provided $|d_0| = 1$:

4. $|d| = 1$ is preserved

Condition $|d| = 1$ preserved, provided $|d_0| = 1$:

Proof.

- ▶ Set $\varphi = |d|^2 - 1$, assume $|d_0| = 1$.

4. $|d| = 1$ is preserved

Condition $|d| = 1$ preserved, provided $|d_0| = 1$:

Proof.

- ▶ Set $\varphi = |d|^2 - 1$, assume $|d_0| = 1$.
- ▶ Elementary identities

$$\partial_t |d|^2 = 2d \cdot \partial_t d, \quad \Delta |d|^2 = 2\Delta d \cdot d + 2|\nabla d|^2, \quad \nabla |d|^2 = 2d \cdot \nabla d.$$

4. $|d| = 1$ is preserved

Condition $|d| = 1$ preserved, provided $|d_0| = 1$:

Proof.

- ▶ Set $\varphi = |d|^2 - 1$, assume $|d_0| = 1$.
- ▶ Elementary identities

$$\partial_t |d|^2 = 2d \cdot \partial_t d, \quad \Delta |d|^2 = 2\Delta d \cdot d + 2|\nabla d|^2, \quad \nabla |d|^2 = 2d \cdot \nabla d.$$

- ▶ Multiply 2nd (LCD) equation with $2d$:

$$\begin{cases} \partial_t \varphi + u \cdot \nabla \varphi &= \Delta \varphi + 2|\nabla d|^2 \varphi && \text{in } \Omega \\ \partial_\nu \varphi &= 0 && \text{on } \partial\Omega, \\ \varphi(0) &= 0 && \text{in } \Omega, \end{cases}$$

4. $|d| = 1$ is preserved

Condition $|d| = 1$ preserved, provided $|d_0| = 1$:

Proof.

- ▶ Set $\varphi = |d|^2 - 1$, assume $|d_0| = 1$.
- ▶ Elementary identities

$$\partial_t |d|^2 = 2d \cdot \partial_t d, \quad \Delta |d|^2 = 2\Delta d \cdot d + 2|\nabla d|^2, \quad \nabla |d|^2 = 2d \cdot \nabla d.$$

- ▶ Multiply 2nd (LCD) equation with $2d$:

$$\begin{cases} \partial_t \varphi + u \cdot \nabla \varphi &= \Delta \varphi + 2|\nabla d|^2 \varphi && \text{in } \Omega \\ \partial_\nu \varphi &= 0 && \text{on } \partial\Omega, \\ \varphi(0) &= 0 && \text{in } \Omega, \end{cases}$$

- ▶ Uniqueness of solution of parabolic convection-reaction diffusion equation
 $\longrightarrow \varphi = 0$, i.e. $|d| = 1$. □

5. Stability of equilibria and asymptotics

Theorem

Each equilibrium z^* in $\mathcal{E}^* = \{0\} \times \{d \in \mathbb{R}^n\}$ is stable in X_γ , i.e.

- ▶ solutions with initial value close to z_* exist globally,
- ▶ converge exponentially in X_γ to some equilibrium for $t \rightarrow \infty$.

5. Stability of equilibria and asymptotics

Theorem

Each equilibrium $z^* \in \mathcal{E}^* = \{0\} \times \{d \in \mathbb{R}^n\}$ is stable in X_γ , i.e.

- ▶ solutions with initial value close to z_* exist globally,
- ▶ converge exponentially in X_γ to some equilibrium for $t \rightarrow \infty$.

Idea

- ▶ Apply Prüss-Simonett-Zacher 2009.

5. Stability of equilibria and asymptotics

Theorem

Each equilibrium $z^* \in \mathcal{E}^* = \{0\} \times \{d \in \mathbb{R}^n\}$ is stable in X_γ , i.e.

- ▶ solutions with initial value close to z_* exist globally,
- ▶ converge exponentially in X_γ to some equilibrium for $t \rightarrow \infty$.

Idea

- ▶ Apply Prüss-Simonett-Zacher 2009.

Theorem

Solutions which are eventually bounded on their maximal interval of existence

- ▶ exist globally,
- ▶ converge to an equilibrium.

5. Stability of equilibria and asymptotics

Theorem

Each equilibrium $z^* \in \mathcal{E}^* = \{0\} \times \{d \in \mathbb{R}^n\}$ is stable in X_γ , i.e.

- ▶ solutions with initial value close to z_* exist globally,
- ▶ converge exponentially in X_γ to some equilibrium for $t \rightarrow \infty$.

Idea

- ▶ Apply Prüss-Simonett-Zacher 2009.

Theorem

Solutions which are eventually bounded on their maximal interval of existence

- ▶ exist globally,
- ▶ converge to an equilibrium.

Idea

- ▶ Energy $E = \frac{1}{2} \int_{\Omega} (|u|^2 + |\nabla d|^2) dx$ is strict Lyapunov functional for (LCD).

5. Stability of equilibria and asymptotics

Theorem

Each equilibrium $z^* \in \mathcal{E}^* = \{0\} \times \{d \in \mathbb{R}^n\}$ is stable in X_γ , i.e.

- ▶ solutions with initial value close to z_* exist globally,
- ▶ converge exponentially in X_γ to some equilibrium for $t \rightarrow \infty$.

Idea

- ▶ Apply Prüss-Simonett-Zacher 2009.

Theorem

Solutions which are eventually bounded on their maximal interval of existence

- ▶ exist globally,
- ▶ converge to an equilibrium.

Idea

- ▶ Energy $E = \frac{1}{2} \int_{\Omega} (|u|^2 + |\nabla d|^2) dx$ is strict Lyapunov functional for (LCD).
- ▶ Apply Köhne-Prüss-Wilke 2010 and previous theorem.

6. Outlook: Non-isothermal (LCD) model

(LCD + ϑ)- Model

6. Outlook: Non-isothermal (LCD) model

(LCD + ϑ)- Model

- ▶ Temperature-dependent coefficients e.g. viscosity.

6. Outlook: Non-isothermal (LCD) model

(LCD + ϑ)- Model

- ▶ Temperature-dependent coefficients e.g. viscosity.
- ▶ New equation for temperature:

6. Outlook: Non-isothermal (LCD) model

(LCD + ϑ)- Model

- ▶ Temperature-dependent coefficients e.g. viscosity.
- ▶ New equation for temperature:
 - ▶ Respects energy preservation,

6. Outlook: Non-isothermal (LCD) model

(LCD + ϑ)- Model

- ▶ Temperature-dependent coefficients e.g. viscosity.
- ▶ New equation for temperature:
 - ▶ Respects energy preservation,
 - ▶ No-flux boundary condition $q \cdot n = 0$ on $\partial\Omega$.

6. Outlook: Non-isothermal (LCD) model

(LCD + ϑ)- Model

- ▶ Temperature-dependent coefficients e.g. viscosity.
- ▶ New equation for temperature:
 - ▶ Respects energy preservation,
 - ▶ No-flux boundary condition $q \cdot n = 0$ on $\partial\Omega$.

Local Existence

6. Outlook: Non-isothermal (LCD) model

(LCD + ϑ)- Model

- ▶ Temperature-dependent coefficients e.g. viscosity.
- ▶ New equation for temperature:
 - ▶ Respects energy preservation,
 - ▶ No-flux boundary condition $q \cdot n = 0$ on $\partial\Omega$.

Local Existence

- ▶ Maximal regularity:

6. Outlook: Non-isothermal (LCD) model

(LCD + ϑ)- Model

- ▶ Temperature-dependent coefficients e.g. viscosity.
- ▶ New equation for temperature:
 - ▶ Respects energy preservation,
 - ▶ No-flux boundary condition $q \cdot n = 0$ on $\partial\Omega$.

Local Existence

- ▶ Maximal regularity:
 - ▶ Velocity: Stokes operator with variable coefficients, Abels-Terasawa 2009.

6. Outlook: Non-isothermal (LCD) model

(LCD + ϑ)- Model

- ▶ Temperature-dependent coefficients e.g. viscosity.
- ▶ New equation for temperature:
 - ▶ Respects energy preservation,
 - ▶ No-flux boundary condition $q \cdot n = 0$ on $\partial\Omega$.

Local Existence

- ▶ Maximal regularity:
 - ▶ Velocity: Stokes operator with variable coefficients, Abels-Terasawa 2009.
 - ▶ Temperature: Denk-Hieber-Prüss 2007.

6. Outlook: Non-isothermal (LCD) model

(LCD + ϑ)- Model

- ▶ Temperature-dependent coefficients e.g. viscosity.
- ▶ New equation for temperature:
 - ▶ Respects energy preservation,
 - ▶ No-flux boundary condition $q \cdot n = 0$ on $\partial\Omega$.

Local Existence

- ▶ Maximal regularity:
 - ▶ Velocity: Stokes operator with variable coefficients, Abels-Terasawa 2009.
 - ▶ Temperature: Denk-Hieber-Prüss 2007.
 - ▶ Director (Δ_N on $H_q^1(\Omega)$): Banach-Scale Argument, Amann 2000.

6. Outlook: Non-isothermal (LCD) model

(LCD + ϑ)- Model

- ▶ Temperature-dependent coefficients e.g. viscosity.
- ▶ New equation for temperature:
 - ▶ Respects energy preservation,
 - ▶ No-flux boundary condition $q \cdot n = 0$ on $\partial\Omega$.

Local Existence

- ▶ Maximal regularity:
 - ▶ Velocity: Stokes operator with variable coefficients, Abels-Terasawa 2009.
 - ▶ Temperature: Denk-Hieber-Prüss 2007.
 - ▶ Director (Δ_N on $H_q^1(\Omega)$): Banach-Scale Argument, Amann 2000.
- ▶ Apply Clement-Li.

6. Outlook: Non-isothermal (LCD) model

(LCD + ϑ)- Model

- ▶ Temperature-dependent coefficients e.g. viscosity.
- ▶ New equation for temperature:
 - ▶ Respects energy preservation,
 - ▶ No-flux boundary condition $q \cdot n = 0$ on $\partial\Omega$.

Local Existence

- ▶ Maximal regularity:
 - ▶ Velocity: Stokes operator with variable coefficients, Abels-Terasawa 2009.
 - ▶ Temperature: Denk-Hieber-Prüss 2007.
 - ▶ Director (Δ_N on $H_q^1(\Omega)$): Banach-Scale Argument, Amann 2000.
- ▶ Apply Clement-Li.

Stability of equilibria and asymptotics

6. Outlook: Non-isothermal (LCD) model

(LCD + ϑ)- Model

- ▶ Temperature-dependent coefficients e.g. viscosity.
- ▶ New equation for temperature:
 - ▶ Respects energy preservation,
 - ▶ No-flux boundary condition $q \cdot n = 0$ on $\partial\Omega$.

Local Existence

- ▶ Maximal regularity:
 - ▶ Velocity: Stokes operator with variable coefficients, Abels-Terasawa 2009.
 - ▶ Temperature: Denk-Hieber-Prüss 2007.
 - ▶ Director (Δ_N on $H_q^1(\Omega)$): Banach-Scale Argument, Amann 2000.
- ▶ Apply Clement-Li.

Stability of equilibria and asymptotics

- ▶ Assume Clausius-Duhem inequality \rightarrow Entropy is strict Lyapunov functional.

6. Outlook: Non-isothermal (LCD) model

(LCD + ϑ)- Model

- ▶ Temperature-dependent coefficients e.g. viscosity.
- ▶ New equation for temperature:
 - ▶ Respects energy preservation,
 - ▶ No-flux boundary condition $q \cdot n = 0$ on $\partial\Omega$.

Local Existence

- ▶ Maximal regularity:
 - ▶ Velocity: Stokes operator with variable coefficients, Abels-Terasawa 2009.
 - ▶ Temperature: Denk-Hieber-Prüss 2007.
 - ▶ Director (Δ_N on $H_q^1(\Omega)$): Banach-Scale Argument, Amann 2000.
- ▶ Apply Clement-Li.

Stability of equilibria and asymptotics

- ▶ Assume Clausius-Duhem inequality \rightarrow Entropy is strict Lyapunov functional.
- ▶ Apply Köhne-Prüss-Wilke 2010, Prüss-Simonett-Zacher 2009.