

A duality principle and a concerning convex dual formulation suitable for non-convex variational optimization

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Abstract

This article develops a duality principle and a related convex dual formulation suitable for a large class of models in physics and engineering. The results are based on standard tools of functional analysis, calculus of variations and duality theory. In particular, we develop applications to a model in non-linear elasticity.

Key words: Convex dual variational formulation, duality principle for non-convex optimization, model in non-linear elasticity

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1 Introduction

In this section we establish a duality principle and a related convex dual formulation for a large class of models in non-convex optimization.

More specifically, the main duality principle is applied to a model in non-linear elasticity.

Such results are based on the works of J.J. Telega and W.R. Bielski [2, 3, 13, 14] and on a D.C. optimization approach developed in Toland [15].

Remark 1.1. *In this text we adopt the standard Einstein convention of summing up repeated indices unless otherwise indicated.*

At this point we start to describe the primal and dual variational formulations.

Let $\Omega \subset \mathbb{R}^3$ be an open, bounded, connected set with a regular (Lipschitzian) boundary denoted by $\partial\Omega$.

For the primal formulation, consider a functional $J : V \rightarrow \mathbb{R}$ where

$$J(u) = \frac{1}{2} \int_{\Omega} H_{ijkl} e_{ij}(u) e_{kl}(u) \, dx - \langle u_i, f_i \rangle_{L^2}. \quad (1)$$

Here $\{H_{ijkl}\}$ is a fourth order symmetric positive definite tensor and

$$\{e_{ij}(u)\} = \left\{ \frac{1}{2}(u_{i,j} + u_{j,i}) + \frac{1}{2}(u_{m,i}u_{m,j}) \right\},$$

where

$$u = (u_1, u_2, u_3) \in V = W_0^{1,2}(\Omega; \mathbb{R}^3)$$

denotes the field of displacements resulting from the action of the external forces $f = (f_1, f_2, f_3) \in L^2(\Omega; \mathbb{R}^3)$ on the elastic solid comprised by $\Omega \subset \mathbb{R}^3$.

Moreover, denoting $Y = Y^* = L^2(\Omega; \mathbb{R}^{3 \times 3})$, the stress tensor $\sigma \in Y^*$ is defined by

$$\{\sigma_{ij}(u)\} = \{H_{ijkl}e_{kl}(u)\}.$$

At this point we define $F_1 : V \times Y \rightarrow \mathbb{R}$, $F_2 : V \rightarrow \mathbb{R}$ and $G : V \rightarrow \mathbb{R}$ by

$$\begin{aligned} F_1(u, \sigma) &= -\frac{K}{2} \int_{\Omega} u_{i,j} u_{i,j} \, dx \\ &\quad + \sum_{i=1}^3 \frac{K_1}{2} \int_{\Omega} (\sigma_{ij,j} + (\sigma_{im} u_{m,j})_{,j} + f_i)^2 \, dx \\ &\quad + \frac{K_2}{2} \int_{\Omega} u_{i,j} u_{i,j} \, dx - \langle u_i, f_i \rangle_{L^2}, \end{aligned} \quad (2)$$

for appropriate positive real constants, K, K_1, K_2 to be specified,

$$F_2(u) = \frac{K_2}{2} \int_{\Omega} u_{i,j} u_{i,j} \, dx,$$

and

$$G(u) = \frac{1}{2} \int_{\Omega} H_{ijkl} e_{ij}(u) e_{kl}(u) \, dx + \frac{K}{2} \int_{\Omega} u_{i,j} u_{i,j} \, dx.$$

Furthermore, we define $F_1^* : [Y^*]^3 \rightarrow \mathbb{R}$, $F_2^* : Y^* \rightarrow \mathbb{R}$ and $G^* : [Y^*]^2 \rightarrow \mathbb{R}$ by

$$F_1^*(\sigma, Q, \tilde{Q}) = \sup_{u \in V} \{ -\langle u_{i,j}, \sigma_{ij} \rangle_{L^2} - \langle u_{i,j}, Q_{ij} \rangle_{L^2} + \langle u_{i,j}, \tilde{Q}_{ij} \rangle_{L^2} - F_1(u, \sigma) \},$$

$$\begin{aligned} F_2^*(\tilde{Q}) &= \sup_{u \in V} \{ \langle u_{i,j}, \tilde{Q}_{ij} \rangle_{L^2} - F_2(u) \} \\ &= \frac{1}{2K_2} \int_{\Omega} \tilde{Q}_{ij} \tilde{Q}_{ij} \, dx, \end{aligned} \quad (3)$$

and

$$G^*(\sigma, Q) = \sup_{(v_1, v_2) \in Y \times Y} \{ \langle (v_1)_{ij}, \sigma_{ij} \rangle_{L^2} + \langle (v_2)_{ij}, Q_{ij} \rangle_{L^2} - \hat{G}(v_1, v_2) \},$$

where

$$\begin{aligned} \hat{G}(v_1, v_2) &= \frac{1}{2} \int_{\Omega} H_{ijkl} \left((v_1)_{ij} + \frac{1}{2}(v_2)_{mi}(v_2)_{mj} \right) \left((v_1)_{kl} + \frac{1}{2}(v_2)_{mk}(v_2)_{ml} \right) \, dx \\ &\quad + \frac{K}{2} \int_{\Omega} u_{i,j} u_{i,j} \, dx, \end{aligned} \quad (4)$$

so that

$$G^*(\sigma, Q) = \frac{1}{2} \int_{\Omega} (\overline{\sigma_{ij}^K}) Q_{mi} Q_{mj} dx + \frac{1}{2} \int_{\Omega} \overline{H_{ijkl}} \sigma_{ij} \sigma_{kl} dx,$$

if $\sigma \in B^*$ where

$$B^* = \{\sigma \in Y^* : \|\sigma_{ij}\|_{\infty} \leq K/8, \forall i, j \in \{1, 2, 3\}\}.$$

Here

$$\{\sigma_{ij}^K\} = \begin{bmatrix} \sigma_{11} + K & \sigma_{12} & \sigma_{13} \\ \sigma_{21} & \sigma_{22} + K & \sigma_{23} \\ \sigma_{31} & \sigma_{32} & \sigma_{33} + K \end{bmatrix} \quad (5)$$

$$\overline{\sigma_{ij}^K} = \{\sigma_{ij}\}^{-1},$$

and

$$\{\overline{H_{ijkl}}\} = \{H_{ijkl}\}^{-1}$$

in an appropriate tensor sense.

At this point we define

$$J^*(\sigma, Q, \tilde{Q}) = -F_1^*(\sigma, Q, \tilde{Q}) + F_2^*(\tilde{Q}) - G^*(\sigma, Q).$$

Specifically for

$$K_2 \gg K_1 \gg K \gg K_3 \gg 1,$$

we define

$$D^* = \{Q \in Y^* : \|Q_{ij}\|_{\infty} \leq K_3, \forall i, j \in \{1, 2, 3\}\}.$$

By direct computation, we may obtain

$$\left\{ \frac{\partial^2 J^*(\sigma, Q, \tilde{Q})}{\partial \sigma \partial Q} \right\} < \mathbf{0},$$

and

$$\left\{ \frac{\partial^2 J^*(\sigma, Q, \tilde{Q})}{\partial \tilde{Q}^2} \right\} > \mathbf{0},$$

on $B^* \times D^* \times Y^*$, so that J^* is concave in (σ, Q) and convex in $\tilde{Q}$ on $B^* \times D^* \times Y^*$.

2 The main duality principle and a related convex dual variational formulation

Our main duality principle is summarized by the following theorem.

Theorem 2.1. *Considering the statements and definitions of the previous section, suppose $(\hat{\sigma}, \hat{Q}, \hat{\tilde{Q}}) \in B^* \times D^* \times Y^*$ is such that*

$$\delta J^*(\hat{\sigma}, \hat{Q}, \hat{\tilde{Q}}) = \mathbf{0}.$$

Let $u_0 \in V$ be such that

$$(u_0)_{i,j} = \frac{\partial F_2^*(\tilde{Q})}{\partial \tilde{Q}_{ij}}.$$

Under such hypotheses, we have

$$\begin{aligned} J(u_0) &= \min_{u \in V} \left\{ J(u) + \sum_{i=1}^3 \frac{K_1}{2} \int_{\Omega} (\hat{\sigma}_{ij,j} + (\hat{\sigma}_{im} u_{m,j})_{,j} + f_i)^2 dx \right\} \\ &= \inf_{\tilde{Q} \in Y^*} \left\{ \sup_{(\sigma, Q) \in B^* \times D^*} J^*(\sigma, Q, \tilde{Q}) \right\} \\ &= J^*(\hat{\sigma}, \hat{Q}, \hat{\tilde{Q}}). \end{aligned} \quad (6)$$

Proof. Observe that there exists $\hat{u} \in V$ such that, defining

$$H(u, \sigma, Q, \tilde{Q}) = -\langle u_{i,j}, \sigma_{ij} \rangle_{L^2} - \langle u_{i,j}, Q_{ij} \rangle_{L^2} + \langle u_{i,j}, \tilde{Q}_{ij} \rangle_{L^2} - F_1(u, \sigma),$$

we have

$$\frac{\partial H(\hat{u}, \hat{\sigma}, \hat{Q}, \hat{\tilde{Q}})}{\partial u} = \mathbf{0}$$

and

$$F_1^*(\hat{\sigma}, \hat{Q}, \hat{\tilde{Q}}) = H(\hat{u}, \hat{\sigma}, \hat{Q}, \hat{\tilde{Q}}).$$

Moreover, from the variation in of J^* in $\tilde{Q}$, we obtain

$$-\frac{\partial F_1^*(\hat{\sigma}, \hat{Q}, \hat{\tilde{Q}})}{\partial \tilde{Q}_{ij}} + \frac{\partial F_2^*(\hat{\tilde{Q}})}{\partial \tilde{Q}_{ij}} = \mathbf{0},$$

where

$$\begin{aligned} &\frac{\partial F_1^*(\hat{\sigma}, \hat{Q}, \hat{\tilde{Q}})}{\partial \tilde{Q}_{ij}} \\ &= \frac{\partial H(\hat{u}, \hat{\sigma}, \hat{Q}, \hat{\tilde{Q}})}{\partial \tilde{Q}_{ij}} \\ &\quad + \frac{\partial H(\hat{u}, \hat{\sigma}, \hat{Q}, \hat{\tilde{Q}})}{\partial u} \frac{\partial \hat{u}}{\partial \tilde{Q}_{ij}} \\ &= \hat{u}_{i,j}. \end{aligned} \quad (7)$$

From such last two equations we get

$$(u_0)_{i,j} = \frac{\partial F_2^*(\hat{\tilde{Q}})}{\partial \tilde{Q}_{ij}} = \frac{\partial F_1^*(\hat{\sigma}, \hat{Q}, \hat{\tilde{Q}})}{\partial \tilde{Q}_{ij}} = \hat{u}_{i,j},$$

so that from the concerning boundary conditions,

$$u_0 = \hat{u}.$$

On the other hand, from the variation of J^* in Q we have

$$-\frac{\partial F_1^*(\hat{\sigma}, \hat{Q}, \hat{\hat{Q}})}{\partial Q_{ij}} - \frac{\partial G^*(\hat{\sigma}, \hat{Q})}{\partial Q_{ij}} = \mathbf{0},$$

so that

$$(u_0)_{i,j} - \overline{\hat{\sigma}_{im}^K} \hat{Q}_{m,j} = 0,$$

and therefore

$$\hat{Q}_{ij} = \hat{\sigma}_{im}(u_0)_{m,j} + K\delta_{ij}(u_0)_{i,j}.$$

Finally, from the variation of J^* in σ we obtain

$$-\frac{\partial F_1^*(\hat{\sigma}, \hat{Q}, \hat{\hat{Q}})}{\partial \sigma_{ij}} - \frac{\partial G^*(\hat{\sigma}, \hat{Q})}{\partial \sigma_{ij}} = \mathbf{0},$$

so that

$$(u_0)_{i,j} + \frac{1}{2}(u_0)_{m,i}(u_0)_{m,j} - \overline{H}_{ijkl}\hat{\sigma}_{kl} = 0.$$

Thus, since $\{H_{ijkl}\}$ is symmetric, we get

$$\hat{\sigma}_{ij} = H_{ijkl}e_{kl}(u_0).$$

From these last results and from

$$\frac{\partial H(\hat{u}, \hat{\sigma}, \hat{Q}, \hat{\hat{Q}})}{\partial u} = \mathbf{0}$$

we obtain

$$\hat{\sigma}_{ij,j} + (\hat{\sigma}_{im}(u_0)_{m,j})_{,j} + f_i = 0, \quad \forall i \in \{1, 2, 3\},$$

so that

$$\delta J(u_0) = \mathbf{0}.$$

Finally, from such last results and the Legendre transform properties, we have

$$\begin{aligned} F_1^*(\hat{\sigma}, \hat{Q}, \hat{\hat{Q}}) \\ = -\langle (u_0)_{i,j}, \hat{\sigma}_{ij} \rangle_{L^2} - \langle (u_0)_{i,j}, \hat{Q}_{ij} \rangle_{L^2} + \langle (u_0)_{i,j}, \hat{\hat{Q}}_{ij} \rangle_{L^2} - F_1(u_0, \hat{\sigma}), \end{aligned} \quad (8)$$

$$F_2^*(\hat{\hat{Q}}) = \langle (u_0)_{i,j}, \hat{\hat{Q}}_{ij} \rangle_{L^2} - F_2(u_0),$$

and

$$G^*(\hat{\sigma}, \hat{Q}) = \langle (u_0)_{i,j}, \hat{\sigma}_{ij} \rangle_{L^2} + \langle (u_0)_{i,j}, \hat{Q}_{ij} \rangle_{L^2} - G(u_0).$$

From these results, we obtain

$$\begin{aligned} J^*(\hat{\sigma}, \hat{Q}, \hat{\hat{Q}}) &= -F_1^*(\hat{\sigma}, \hat{Q}, \hat{\hat{Q}}) + F_2^*(\hat{\hat{Q}}) - G^*(\hat{\sigma}, \hat{Q}) \\ &= F_1(u_0, \hat{\sigma}) - F_2(u_0) + G(u_0) \\ &= J(u_0). \end{aligned} \quad (9)$$

Joining the pieces, we have got

$$\begin{aligned}
 J(u_0) &= \min_{u \in V} \left\{ J(u) + \sum_{i=1}^3 \frac{K_1}{2} \int_{\Omega} (\hat{\sigma}_{ij,j} + (\hat{\sigma}_{im} u_{m,j})_{,j} + f_i)^2 dx \right\} \\
 &= \inf_{\tilde{Q} \in Y^*} \left\{ \sup_{(\sigma, Q) \in B^* \times D^*} J^*(\sigma, Q, \tilde{Q}) \right\} \\
 &= J^*(\hat{\sigma}, \hat{Q}, \hat{\tilde{Q}}).
 \end{aligned} \tag{10}$$

The proof is complete. □

3 Conclusion

In this article we have developed a convex dual variational formulation suitable for non-convex variational primal formulations.

It is worth highlighting, the results may be applied to a large class of models in physics and engineering.

We also emphasize the duality principle here presented is applied to a model in non-linear elasticity. In a future research, we intend to extend such results for other related models of plates and shells.

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