Imperial College London

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Coherence and Regularity of Modelled Distributions

Higher structures emerging from renormalisation - ESI

Ajay Chandra (Imperial College London) joint work with Timothee Bonnefoi, Augustin Moinat, and Hendrik Weber (Bath) **Motivation:** Want a systematic understanding of how to glue together deterministic ODE/PDE arguments at larger time (and space) scales with local solution theory from Gubinelli's Branched Rough Paths/Hairer's Theory of Regularity Structures to get a priori bounds on solutions with the aim of getting global in time (and space) well-posedness.

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Recent work: Studying equations with strong damping terms and proving strong "coming down from infinity" type bounds:

The Φ^4 equation:

$$(\partial_t - \Delta) arphi = - arphi^3 + \xi$$
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where formally $\varphi : \mathbb{R}_+ \times \mathbb{R}^d \to \mathbb{R}$ and ξ is a rough random space-time process (like space-time white noise).

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Previous work on a priori bounds/global well-posedness: For for Φ_3^4 : [Mourrat, Weber], [Gubinelli, Hofmanová], [Albeverio, Kusuoka], [Moinat, Weber] [C., Moinat, Weber] extends analysis to the entire subcritical/super-renormalizable regime. Rough Differential Equations with strong damping:

$$\partial_t Y(t) = -|Y(t)|^{m-1}Y(t)dt + \sum_{\mu=1}^d \sigma_\mu(Y(t))dX^\mu(t)$$

where m > 1, $Y : \mathbb{R}_+ \to \mathbb{R}^k$ and $X = (X^{\mu})_{\mu=1}^d : \mathbb{R}_+ \to \mathbb{R}^d$ is a rough (α -Hölder, for $\alpha > 0$ but arbitrarily small) driving noise, and $\sigma_{\mu} : \mathbb{R}^k \to \mathbb{R}^k$ are relatively nice vector fields.

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Previous work on this class of equations by [Riedel, Scheutzow]. Joint work in progress using approach from SPDE with Bonnefoi, Moinat, and Weber. Example of coming down from infinite bound: if σ_{μ} has a certain class of derivatives bounded and if Y solves the above equation on [0, 1] then

$$\sup_{t \in (0,1]} |Y(t)| \lesssim \max\{t^{-\frac{1}{m-1}}, \max_{h \in \mathring{\mathcal{T}}} [X:h]^{\frac{1}{m\alpha|h|}}\}$$

uniformly over the initial data $Y(0)$.

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- Solution: Can construct new spaces of function/distributions that admit good local approximations (non-classical Taylor Expansions) in terms of these iterated integrals - and the equation can be reformulated on this space in a way that makes it locally well-posed there.

Average entire equation at some scale L:

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$$\dot{Y}_L(t) = -|Y_L(t)|^{m-1}Y_L(t) + \left(\sum_{\mu=1}^d \sigma_\mu(Y(t))dX^\mu(\bullet)\right)_L$$

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- Solution Algebra/Combinatorics: Can show that a solution to a Rough Differential Equation has additional relations between these generalised derivatives (*coherence* - [Bruned, Chevyrev, Preiß, Friz], [Bruned, Chevyrev, C., Hairer])

Quick overview of branched Rough Paths

• Let $N = \lfloor \frac{1}{\alpha} \rfloor$, we define $\mathring{\mathcal{T}}$ to consist of all rooted trees with no more than N nodes, each of which is decorated by the set $\{1, \ldots, d\}$.

▶ Driving noise along with Iterated integrals encoded by map $X_{s,t} : T \to \mathbb{R}, T \ni h \mapsto \langle X_{s,t}, h \rangle.$

$$\langle \mathbf{X}_{s,t}, \bullet_{\mathbf{i}} \rangle = \int_{s}^{t} dX^{i}(r) = X^{i}(t) - X^{i}(s)$$

$$\langle \mathbf{X}_{s,t}, \bullet_{\mathbf{i}} \rangle = \int_{s}^{t} \int_{s}^{r_{1}} dX^{i}(r_{2}) dX^{j}(r_{1})$$

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$$\langle \mathbf{X}_{s,t}, \bullet_{\mathbf{i}} \rangle = \int_{s}^{t} \left(\int_{s}^{r_{1}} dX^{i}(r_{2}) \right)^{2} dX^{j}(r_{1})$$

• We define \mathcal{F} to be the set of forests of trees in $\mathring{\mathcal{T}}$. We also set $\mathcal{T} = \{\mathbb{1}\} \sqcup \mathring{\mathcal{T}}$.

►
$$\Delta : \operatorname{Span}(\mathcal{F}) \to \operatorname{Span}(\mathcal{F}) \otimes \operatorname{Span}(\mathcal{F}) \text{ is the Grassman-Larson}$$

co-product
 $\Delta \checkmark = 1 \otimes \checkmark + \checkmark \otimes 1 + \checkmark \otimes 1 + \circ \otimes 1 +$

đ

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• We call **X** a branched rough path if for all $h \in \mathring{\mathcal{T}}$,

$$\begin{split} [\mathbf{X},h] &\stackrel{\text{\tiny def}}{=} \sup_{0 < |s-t| < 1} \Big| \frac{\langle \mathbf{X}_{s,t},h \rangle}{|s-t|^{\alpha|h|}} \Big| < \infty \\ \text{and } \langle \mathbf{X}_{s,u} \otimes \mathbf{X}_{u,t}, \Delta h \rangle = \langle \mathbf{X}_{s,t},h \rangle \end{split}$$

Our solution is a Controlled Rough Path: $\mathbf{Y} : [0, 1] \to \operatorname{Span}(\mathcal{T})$, that is a family of local expansions $\mathbf{Y}_{s} = \sum_{h \in \mathcal{T}} \langle h, \mathbf{Y}_{s} \rangle h = Y_{s} \mathbb{1} + \sum_{h \in \mathring{\mathcal{T}}} \langle h, \mathbf{Y}_{s} \rangle h$. $\begin{array}{c} \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h = Y_{s} \mathbb{1} + \sum_{h \in \mathring{\mathcal{T}}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h = Y_{s} \mathbb{1} + \sum_{h \in \mathring{\mathcal{T}}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h = Y_{s} \mathbb{1} + \sum_{h \in \mathring{\mathcal{T}}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h = Y_{s} \mathbb{1} + \sum_{h \in \mathring{\mathcal{T}}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h = Y_{s} \mathbb{1} + \sum_{h \in \mathring{\mathcal{T}}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h = Y_{s} \mathbb{1} + \sum_{h \in \mathring{\mathcal{T}}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h = Y_{s} \mathbb{1} + \sum_{h \in \mathring{\mathcal{T}}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h = Y_{s} \mathbb{1} + \sum_{h \in \mathring{\mathcal{T}}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h = Y_{s} \mathbb{1} + \sum_{h \in \mathring{\mathcal{T}}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h = Y_{s} \mathbb{1} + \sum_{h \in \mathring{\mathcal{T}}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h = Y_{s} \mathbb{1} + \sum_{h \in \mathring{\mathcal{T}}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr{T}} \langle h, \mathbf{Y}_{s} \rangle h \\ \mathcal{Y}_{s} = \int_{h \in \mathscr$ Our solution is a Controlled Rough Path: $\mathbf{Y} : [0,1] \to \operatorname{Span}(\mathcal{T})$, that is a family of local expansions

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Space of controlled rough paths is a vector space where we can solve the equation as a fixed point problem, but in this space there are no clear relations between $R_{s,t}^h$ for different h.

$$\Upsilon[h] pprox (D^n \sigma_\mu) \prod_{j=1}^n \Upsilon[h]$$
 with base cases $\Upsilon[\quad] = \sigma_\mu$.

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$$\bigvee \cdot j \approx \psi = \bigvee + \bigvee + \cdots$$

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$$\Upsilon[\tilde{f} \frown h] \approx (D^n \Upsilon[h]) \prod_{j=1}^n \Upsilon[\tilde{h_j}].$$

Combining this with the adjoint relation $\langle \tilde{f} \otimes h, \Delta \bar{h} \rangle \approx \langle \tilde{f} \frown h, \bar{h} \rangle$ allows us to show that

 $|R_{s,t}^h| \lesssim |\nabla \Upsilon[h](Y_s)| \cdot |R_{s,t}^{\mathbb{1}}| + \text{ higher order terms}$

which allows us to close our ODE argument!

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