

# Alice in Stretch & SqueezeLand: 4 Topology of Orbits

August 12, 2012

# Chapter Abstract

Alice in  
Stretch &  
SqueezeLand:  
4 Topology  
of Orbits

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Summary-01

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Orbits-01

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Orbits-02

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Periodic orbits exist in abundance in a strange attractor.

The problems are: to find them, to determine how they are organized among themselves.

Whatever mechanism exists to create the strange attractor, it simultaneously organizes all the unstable periodic orbits in the attractor in a unique way.

We can classify *mechanisms* by sets of *integers*.

There is an *Aufbau Principal* for building up strange attractors.

## Chaos

### Motion that is

- **Deterministic:**  $\frac{dx}{dt} = f(x)$
- **Recurrent**
- **Non Periodic**
- **Sensitive to Initial Conditions**

## Strange Attractor

The  $\Omega$  limit set of the flow. There are unstable periodic orbits “in” the strange attractor. They are

- “Abundant”
- Outline the Strange Attractor
- Are the Skeleton of the Strange Attractor

# UPOs: Skeletons of Strange Attractors

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**Topology of  
Orbits-03a**

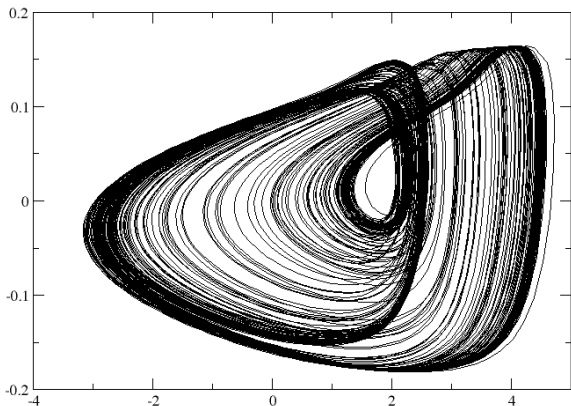
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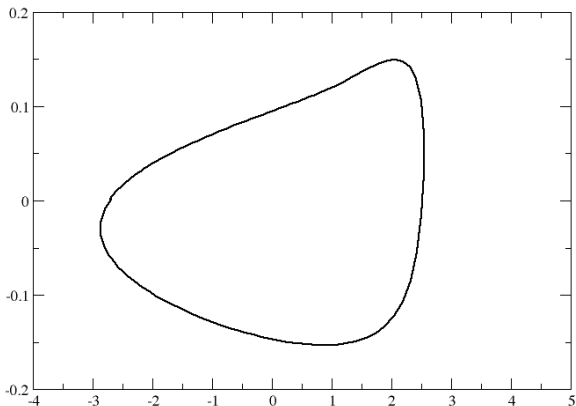
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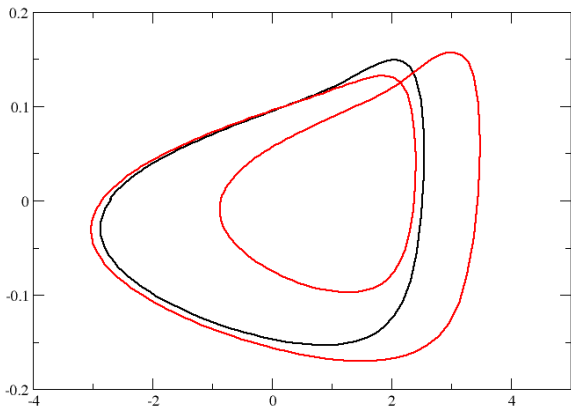
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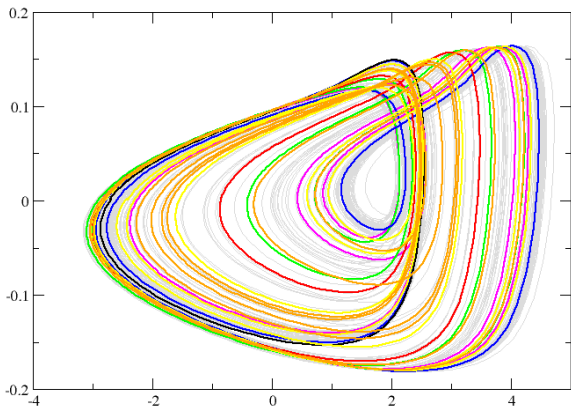
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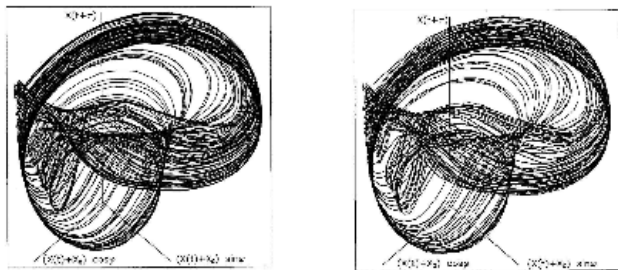
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## UPOs Outline Strange Attractors



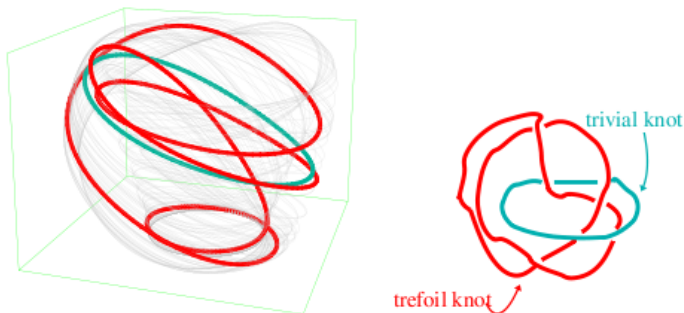
**Figure 5.** Left: a chaotic attractor reconstructed from a time series from a chaotic laser ; Right : Superposition of 12 periodic orbits of periods from 1 to 10.

## Organization of UPOs in $R^3$ : Gauss Linking Number

$$LN(A, B) = \frac{1}{4\pi} \oint \oint \frac{(\mathbf{r}_A - \mathbf{r}_B) \cdot d\mathbf{r}_A \times d\mathbf{r}_B}{|\mathbf{r}_A - \mathbf{r}_B|^3}$$

# Interpretations of  $LN \simeq$  # Mathematicians in World

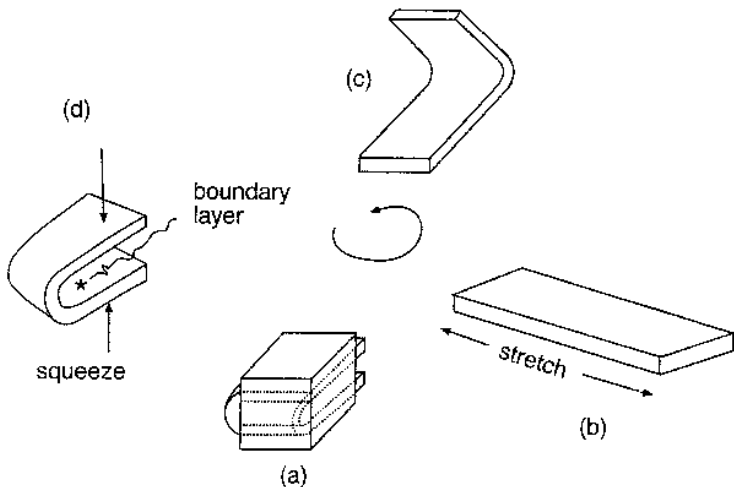
## Linking Number of Two UPOs



**Figure 6.** Left: two periodic orbits of periods 1 and 4 embedded in a strange attractor; Right: a link of two knots that is equivalent to the pair of periodic orbits up to continuous deformations without crossings.

# Mechanisms for Generating Chaos

## Stretching and Folding



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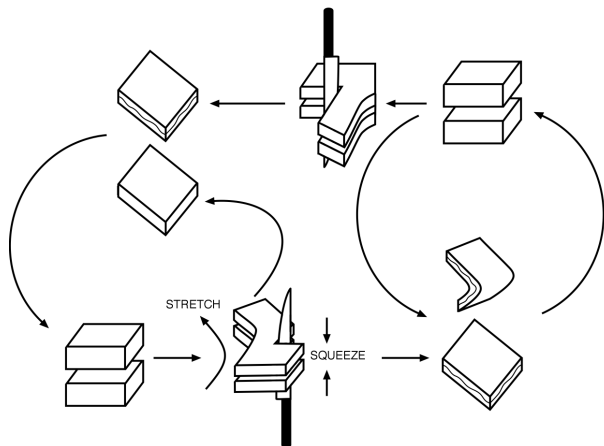
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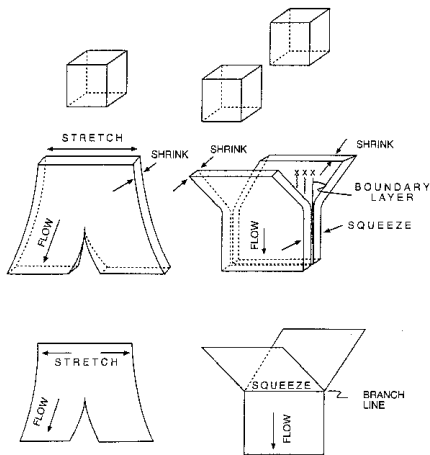
# Mechanisms for Generating Chaos

## Tearing and Squeezing



# Motion of Blobs in Phase Space

## Stretching — Squeezing

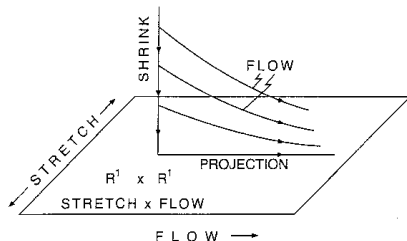


# Collapse Along the Stable Manifold

## Birman - Williams Projection

Identify  $x$  and  $y$  if

$$\lim_{t \rightarrow \infty} |x(t) - y(t)| \rightarrow 0$$



## Birman - Williams Theorem

**If:**

**Then:**



## Birman - Williams Theorem

**If:**                      **Certain Assumptions**

**Then:**

## Birman - Williams Theorem

**If:**                      **Certain Assumptions**

**Then:**                    **Specific Conclusions**

## Assumptions, B-W Theorem

**A flow**  $\Phi_t(x)$

- on  $R^n$  is dissipative,  $n = 3$ , so that  
 $\lambda_1 > 0, \lambda_2 = 0, \lambda_3 < 0, \quad \lambda_1 + \lambda_2 + \lambda_3 < 0$
- Generates a hyperbolic strange attractor  $SA$

IMPORTANT: The underlined assumptions can be relaxed.

## Conclusions, B-W Theorem

- The projection maps the strange attractor  $\mathcal{SA}$  onto a 2-dimensional branched manifold  $\mathcal{BM}$  and the flow  $\Phi_t(x)$  on  $\mathcal{SA}$  to a semiflow  $\bar{\Phi}(x)_t$  on  $\mathcal{BM}$ .
- UPOs of  $\Phi_t(x)$  on  $\mathcal{SA}$  are in 1-1 correspondence with UPOs of  $\bar{\Phi}(x)_t$  on  $\mathcal{BM}$ . Moreover, every link of UPOs of  $(\Phi_t(x), \mathcal{SA})$  is isotopic to the correspond link of UPOs of  $(\bar{\Phi}(x)_t, \mathcal{BM})$ .

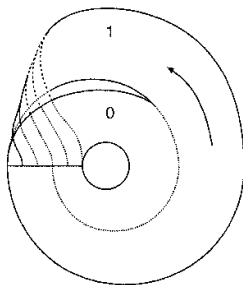
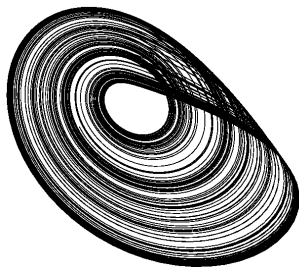
Remark: “One of the few theorems useful to experimentalists.”

# A Very Common Mechanism

**Rössler:**

**Attractor**

**Branched Manifold**

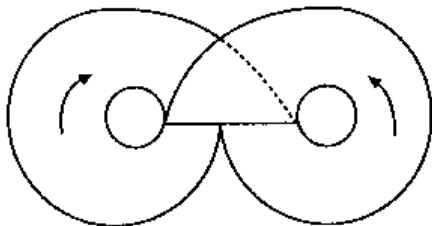
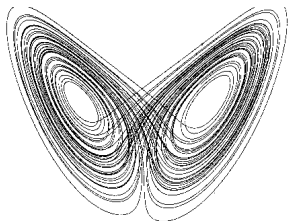


# A Mechanism with Symmetry

**Lorenz:**

**Attractor**

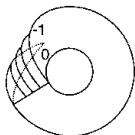
**Branched Manifold**



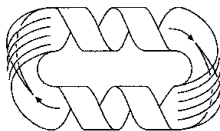
# Examples of Branched Manifolds

## Inequivalent Branched Manifolds

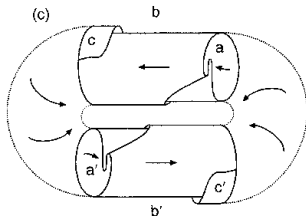
(a)



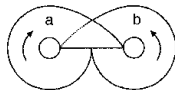
(b)



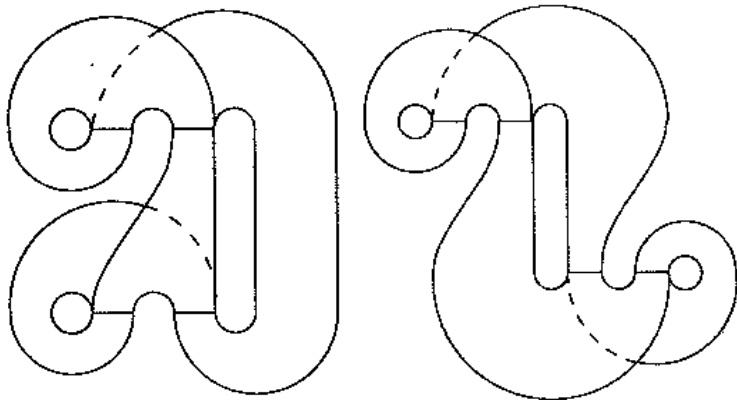
(c)



(d)



## Template Holding All Knot Types



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# Aufbau Princip for Branched Manifolds

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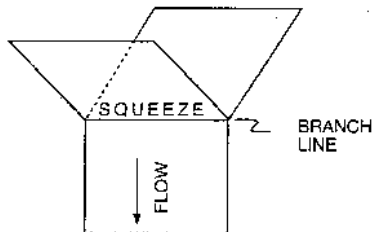
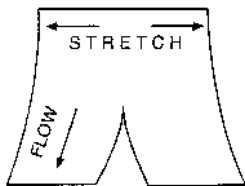
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Any branched manifold can be built up from stretching and squeezing units



subject to the conditions:

- Outputs to Inputs
- No Free Ends

## Rössler System

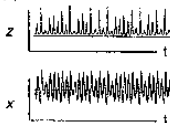
(a) Rössler Equations

$$\frac{dx}{dt} = -y - z$$

$$\frac{dy}{dt} = x + ay$$

$$\frac{dz}{dt} = b + z(x - c)$$

(b)



(c)



(f)

$$\begin{pmatrix} -1 & 0 \\ 0 & 0 \end{pmatrix}$$

$$\begin{pmatrix} 0 & +1 \end{pmatrix}$$

(e)



(f)



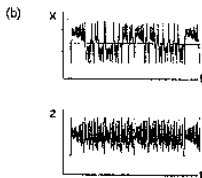
## Lorenz System

(a) Lorenz Equations

$$\frac{dx}{dt} = -\alpha x + \alpha y$$

$$\frac{dy}{dt} = \beta x - y - xz$$

$$\frac{dz}{dt} = -bz + xy$$

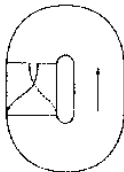


(f)

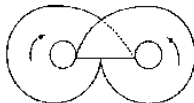
$$\begin{pmatrix} 0 & 0 \\ 0 & 0 \end{pmatrix}$$

$$\begin{pmatrix} +i & -i \end{pmatrix}$$

(e)



(d)



## Poincaré Smiles at $U$ s in $R^3$

- Determine organization of UPOs  $\Rightarrow$
- Determine branched manifold  $\Rightarrow$
- Determine equivalence class of  $\mathcal{SA}$