

Approximate viability for nonlinear evolution inclusions with application to controllability*

Omar Benniche[†] Ovidiu Cârja[‡] Smaïl Djebali[§]

Abstract

We investigate approximate viability for a graph with respect to fully nonlinear quasi-autonomous evolution inclusions. As application, an approximate null controllability result is given.

MSC: primary 34G20; secondary 47J35

keywords: approximate viability; tangency conditions; graph; approximate null controllability.

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[†]obenniche@gmail.com, Department of Mathematics, Djilali Bounaama University, Laboratory "Energie et les Systèmes Intelligents (LESI)", Khemis Miliana, 442500, Algeria and Laboratory "Théorie de Point Fixe et Applications (TPFA)", ENS, BP 92, 16050, Algiers, Algeria; Paper written with financial support by a grant of the Ministry of Higher Education and Scientific Research Algerian, project number 265/PNE/Roumanie/2015-2016

[‡]ocarja@uaic.ro, Department of Mathematics, "Al. I. Cuza" University, Iași, 700506, Romania and Octav Mayer Institute of Mathematics (Romanian Academy), Iași 700505, Romania; Paper written with financial support by a grant of the Romanian National Authority for Scientific Research, CNCS-UEFISCDI, project number PN-II-ID-PCE-2011-3-0154

[§]djebali@hotmail.com, Laboratory "Théorie de Point Fixe et Applications (TPFA)", ENS, BP 92, 16006, Algiers, Algeria and Department of Mathematics, Faculty of Sciences, IMAMU University. P.O. Box 90950, Riyadh 11623, Saudi Arabia