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Properties of certain iterated dynamic integrodifferential equation on time scales

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Abstract

The main objective of this paper is study the existence, uniqueness and other properties of solution of some iterated dynamic integrodifferential on time scales. The main tools employed are Banach Fixed Point theorem and an inequality with explicit estimates are used for proving our results.

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Introduction

In last few decades notable contributions have been made in the theory of dynamical equations on time scales and its applications. The theory of time scale was initiated by [Levinson \[1\]](#), [Strohmer \[2\]](#), [Saker \[3\]](#), [Džurina \[4\]](#), [Džurina \[5\]](#), [Džurina \[6\]](#), [Džurina \[7\]](#), [Džurina \[8\]](#), [Džurina \[9\]](#), [Džurina \[10\]](#), [Džurina \[11\]](#), [Džurina \[12\]](#). Many applications as approximation

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to partial differential equations. Dynamic Integral and Integrodifferential on time scales is found to be valuable phenomena in the field of Science and Engineering [10]. Integrodifferential equation with boundary conditions has applications in study of Population dynamics and optimal control problems [14].

The problems of Existence, Uniqueness and other properties of solutions for dynamic equations on time scales have been recently treated in using various techniques such as Leray Schauder, Brower theory and fixed point theorems [1], [2], [11], [15], [16], [20]. Basic of partial differential equations are given in [13].

Recently lot of attention has been devoted to the study of linear and nonlinear dynamic inequalities on time scales which are used in study of Dynamic equations and obtaining explicit estimates [17], [18], [19]. In [3], [4], [5], [9] authors have studied Wendroff type inequalities using Picard's operator and various type of other inequalities in two independent variables on time scales.

Motivated by the above results in this paper we investigate the existence, uniqueness and other properties of the iterated dynamic integrodifferential equation on time scales of

the form $x^\Delta(t) = f\left(t, x(t), \int_{t_0}^t g\left(t, s, x(s), \int_{t_0}^s h(t, \tau, x(\tau)) \Delta\tau\right) \Delta s\right), x(t_0) = x_0$, for

$0 \leq t < \infty$ where x is unknown function to be found $h: I_T^2 \times R^n \rightarrow R^n$, $g: I_T^2 \times R^n \times R^n \rightarrow R^n$, $f: I_T \times R^n \times R^n \rightarrow R^n$, $x_0 \in R^n$, x^Δ is the generalized delta derivative of x , t is form time scale T which is nonempty closed subset of R the set of real numbers and $I_T = I \cap T$.

Section snippets

Preliminaries

In this section we shall introduce some preliminaries and notations which are used throughout this paper. We assume that the time scale T has a topology that it inherits from the real number R with standard topology. We define the jump operators σ, ρ on T by the two mapping $\sigma, \rho: T \rightarrow R$ satisfying conditions

$\sigma(t) = \inf\{s \in T: s > t\}$, $\rho(t) = \sup\{s \in T: s < t\}$. The jump operators classify the points of time scale T as left dense, left scattered, right dense and right scattered according to whether $\rho(t) = t$ or $\rho(t) < t$, $\sigma \dots$

Main results

Now first we prove the dynamic inequality which is used for study of various properties

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Theorem 3.1

Let $x(t), p(t) \in C_{rd}(I_T, R_+)$, $k(t, s) \in C_{rd}(I_T^2, R_+)$ and $q(t, s, \tau) \in C_{rd}(I_T^2 \times R_+, R_+)$ be rd-continuous function for $0 \leq \tau \leq s \leq t < \infty$. If

$x(t) \leq c + \int_{t_0}^t \left[p(s)x(s) + \int_{t_0}^s \left\{ k(s, \tau)x(\tau) + \int_{t_0}^{\tau} q(s, \tau, \eta)x(\eta) \Delta\eta \right\} \Delta\tau \right] \Delta s$, for $t \in T$ where $c \geq 0$ is a constant, $k(t, s) \cdot x(s) \in C_{rd}(I_T^2, R_+)$ and $q(t, s, \tau) \cdot x(\tau) \in C_{rd}(I_T^2 \times R_+, R_+)$ then $x(t) \leq ce_H(t, t_0)$, for $t \in T$ where $H(t) = p(t) + \int_{t_0}^t \left[k(t, s) + \int_{t_0}^s q(t, s, \tau) \Delta\tau \right] \Delta s \dots$

Proof

Define a function $z(t)$...

...

Estimates on the solution

Now in this section we present some basic properties of solutions of Eqs. (1.1) and (1.2) under suitable conditions

Theorem 4.1

Suppose that the functions f, g, h in Eq. (1.1) are rd-continuous and satisfy the conditions

$$|f(t, u, v) - f(t, \bar{u}, \bar{v})| \leq p(t) |u - \bar{u}| + |v - \bar{v}|,$$

$$|g(t, \tau, v, w) - g(t, \tau, \bar{v}, \bar{w})| \leq k(t, \tau) |v - \bar{v}| + |w - \bar{w}|,$$

$$|h(t, s, v) - h(t, s, \bar{v})| \leq q(t, s, \tau) |v - \bar{v}|, \text{ where } p, q, k \text{ are as in Theorem 3.1. Let}$$

$$c_2 = \left| x_0 + \int_{t_0}^t f\left(s, 0, \int_{t_0}^s g\left(s, \tau, 0, \int_{t_0}^{\tau} h(t, \eta, 0) \Delta\eta\right) \Delta\tau\right) \Delta s \right|. \text{ If } x(t), t \in I_T \text{ is any solution of (1.1),}$$

then $|x(t)| \leq c_2 e_H(t, t_0)$, where H is given...

...

Continuous dependence

Now in this section we study the continuous dependence of solution of Eqs. (1.1) and (1.2) on the functions involved therein. Consider an equation (1.1)-(1.2) and the

$$\text{corresponding equation } y^{\Delta}(t) = \bar{f}\left(t, y(t), \int_{t_0}^s \bar{g}\left(s, \tau, y(\tau), \int_{t_0}^{\tau} \bar{h}(\tau, \eta, y(\eta)) \Delta\eta\right) \Delta\tau\right),$$

$y(t_0) = y_0$, for $t \in I_T$ where $\bar{f}: I_T \times R^n \times R^n \rightarrow R^n$, $\bar{h}: I_T^2 \times R^n \rightarrow R^n$, $\bar{g}: I_T^2 \times R^n \times R^n \rightarrow R^n$ and y_0 is a given constant in R^n .

Theorem 5.1

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Suppose that the functions f, g and h in Eqs. (1.1) and (1.2) satisfy the conditions (4.1)–(4.3). Let $y(t)$ be a given solution of Eqs. (5.1) and (5.2) ...

...

Application

Many times it is difficult to find explicit solution of equation of form (1.1). Integral inequality with explicit estimates is a powerful tool which can be used in studying dynamic equation on time scales. Now we give an example

Example 6.1

Consider linear dynamic equation $y^\Delta(t) = p(t)y(t)$, $y(t_0) = y_0$, and the corresponding perturbed dynamic equation as

$$x^\Delta(t) = p(t)x(t) + f\left(t, x(t), \int_{t_0}^t g\left(t, s, x(s) \int_{t_0}^s h(t, s, \tau, x(\tau)) \Delta\tau\right) \Delta s\right), x(t_0) = y_0, \text{ for } t, t_0 \in T \text{ where } y_0 \text{ is given constant, } p \in \mathfrak{R}, f: I_T \times R^n \times R^n \rightarrow R^n, g: I_T^2 \times R^n \times R^n \rightarrow R^n \text{ and } h: I_T^2 \times R^n \rightarrow R^n.$$

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