

## Lecture 3: Weak-strong uniqueness, relative energy and gradient flow calibration.

Last time we've seen weak solution concepts. The key ingredient to proving the last theorem is the following relative energy

$$\begin{aligned}\mathcal{E}[x|\xi] &:= E[x] + \int_{\mathbb{R}^d} \xi \cdot \nabla x \\ &= \int_{\mathbb{R}^d} (1 - \xi \cdot \nu) |\nabla x| \\ &= \int_{\mathbb{R}^d} \frac{1}{2} |\nu - \xi|^2 |\nabla x| + \int_{\mathbb{R}^d} (1 - |\xi|^2) |\nabla x|.\end{aligned}$$

The key are the following two statements.

Lemma 1 If  $x \in BV$  and  $\varepsilon > 0$  then  $\exists \xi \in C_c^1(\mathbb{R}^d)^d$  s.t.

$$\mathcal{E}[x|\xi] < \varepsilon.$$

Lemma 2 If  $x_n \rightarrow x$  in  $L^1$  and  $E[x_n] \rightarrow E[x]$ , then

$$\mathcal{E}[x_n|\xi] \xrightarrow{n \rightarrow \infty} \mathcal{E}[x|\xi]$$

for any  $\xi \in C_c^1(\mathbb{R}^d)^d$ .

Today, we want to exploit  $\mathcal{E}$  to prove the uniqueness:

Theorem If  $(\Sigma(t) = \partial\Omega(t))_{t \in [0, T]}$  is a smooth MCF and

$X$  is a De Giorgi sol. to MCF on  $[0, T)$  w/ initial

data  $x_0 = X_{\Omega_0}$ , then

$$X(x, t) = X_{\Omega_t}(x) \text{ for a.e. } (x, t) \in \mathbb{R}^d \times (0, T).$$

The key idea is to use the smoothness of  $\Sigma(t)$  to construct a suitable vector field  $\xi(x, t)$  s.t.

$$(*) \quad \frac{d}{dt} E[X|\xi] \leq E[X|\xi].$$

This is a lengthy computation — see the arXiv notes — but the idea is very simple. Let's first get some intuition from the static case.

Theorem Suppose  $\Sigma = \partial\Omega$  is a smooth surface and

$\exists \xi \in C^\infty(\bar{D})^d$  s.t.

$$\nabla \cdot \xi = 0 \text{ in } \bar{D}$$

" $\xi = \text{calibration}$ "

$$\xi = \nu \text{ on } \Sigma$$

$$\int_D |\nabla X|$$

$$|\xi| \leq 1 \text{ in } \bar{D}$$

Then  $E_D[X_\xi] \leq E[X] \quad \forall X \text{ w/ } X = X_\Omega \text{ on } \partial\Omega.$

Pf:  $E[X_\xi] = \int_D |\nabla X_\xi| = \int_D \xi \cdot \nu |\nabla X_\xi| = - \int_D \xi \cdot \nabla X_\xi$

$$= \int_D X_\xi \nabla \cdot \xi dx + \int_{\partial\Omega} X_\xi \nu \cdot \xi d\mathcal{H}^{d-1}.$$

$D$

The idea is to construct a dynamic version of a calibration to prove (\*). Let's at least start the computation:

$$\begin{aligned} \frac{d}{dt} \mathbb{E}[x | \xi] &= \underbrace{\frac{d}{dt} E[x]}_{\leq -\frac{1}{2} \int v^2 |Dx| - \frac{1}{2} \int H^2 |Dx|} - \underbrace{\frac{d}{dt} \int_{\mathbb{R}^d} x (\nabla \cdot \xi) dx}_{= (\partial_t x, \nabla \cdot \xi)} \\ &= \int (\nabla \cdot \xi) v |Dx| + \int \partial_t \xi \cdot v |Dx| \\ &\leq \int \left( -\frac{1}{2} v^2 + (\nabla \cdot \xi) v \right) |Dx| \\ &\quad + \int -\frac{1}{2} H^2 |Dx| \\ &\quad + \int \partial_t \xi \cdot v |Dx| \end{aligned}$$

Idea:  $\cdot \xi = \text{extension of } v_\xi = (\text{cutoff fct}) \cdot \nabla \text{dist}(x, \Sigma_t)$

Because the computation is too long, we'll prove a simpler, but weaker, statement.

Theorem (Inclusion principle) Suppose  $(\Sigma(t) = \partial\Omega(t))_{t \in [0, T]}$  is a smooth MCF and suppose  $\chi: \mathbb{R}^d \times (0, T) \rightarrow \{0, 1\}$  satisfies

$$\frac{d}{dt} \int_{\mathbb{R}^d} \varphi |Dx| \leq \int_{\mathbb{R}^d} \left( -\varphi H^2 + H v \cdot \nabla \varphi + \partial_t \varphi \right) |Dx|$$

for all smooth  $\varphi \geq 0$ .

If  $|Dx_{t_0}| = |Dx(\cdot, t)|$ , then  $|Dx(\cdot, t)| \leq |Dx_{t_0}|$  for a.e.  $t \in (0, T)$ .

Proof: • Key idea: Take  $\varphi \approx \frac{1}{2} \text{dist}^2(x, \Sigma_t)$ , and show that

$$\tilde{\Sigma} = \int \varphi |\mathcal{D}x|$$

satisfies

$$\frac{d}{dt} \tilde{\Sigma} \leq C \tilde{\Sigma}.$$

Exercise:  $s(x,t) := \text{dist}(x, \Sigma_t)$  solves

$$\partial_t s - \Delta s = 0 \text{ on } \Sigma_t$$

and  $\varphi$  solves

$$\cdot \partial_t \varphi - \Delta \varphi \leq -1 + C\varphi \text{ in a nbhd of } \Sigma_t.$$

$$\cdot \nabla^2 \varphi \leq I \quad \text{--- " ---}$$

Then we compute

$$\begin{aligned} \frac{d}{dt} \tilde{\Sigma} &\leq \int_{\mathbb{R}^d} (-\varphi H^2 + H v \cdot \nabla \varphi + \partial_t \varphi) |\mathcal{D}x| \\ &= \int_{\mathbb{R}^d} (-\varphi H^2 - \Delta \varphi + v \cdot \nabla^2 \varphi v + \partial_t \varphi) |\mathcal{D}x| \\ &\leq \int C\varphi |\mathcal{D}x| = C \tilde{\Sigma}. \end{aligned}$$

□

However, the fictional  $\tilde{\Sigma}$  does not enjoy good coercivity properties. In fact, the above proof applies to any Brakke flow (in place of  $\Sigma$ ) so that the argument cannot prove uniqueness.

A better functional would be \*

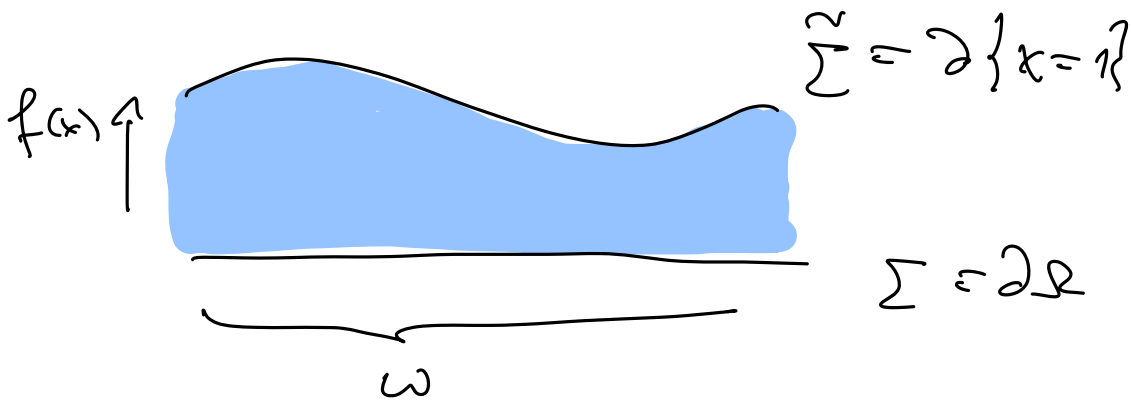
$$\mathcal{F}[x|\Sigma] := \int_{\mathbb{R}^d} \text{sdist}(\cdot, \Sigma) (x - x_\Sigma) dx$$

$$= \int_{\mathbb{R}^d} |\text{sdist}(\cdot, \Sigma)| |x - x_\Sigma| dx$$

\*:  $\text{sdist}(\cdot, \Sigma)$  has to be treated to get a smooth fct - omitted here. because

$$\mathcal{F}[x|\Sigma] \Rightarrow x = x_\Sigma \text{ a.e. in } \mathbb{R}^d.$$

Also this functional is a proxy for the squared  $L^2$ -distance of surfaces



In this case

$$2\mathcal{F} = \int_{\omega} \int_0^{f(x')} 2r dr dx' = \int_{\omega} f^2(x') dx',$$

just like  $\tilde{\Sigma}$ , which in this case reads

$$\tilde{\Sigma} = \int_{\omega} f^2(x') dx'.$$

Let's compute

$$\frac{d}{dt} \mathcal{F}[\chi|\Omega](t) = \int_{\mathbb{R}^d} \partial_t \text{sdist}(x, \partial\Omega(t)) (\chi - \chi_\Omega) dx + \int_{\mathbb{R}^d} \text{sdist}(x, \partial\Omega(t)) \nabla |\chi|$$

$B = H\nu$



$$\leq \int_{\mathbb{R}^d} (B \cdot \nabla) \text{sdist}(x, \partial\Omega(t)) (\chi - \chi_\Omega) dx + C \int_{\mathbb{R}^d} |\text{sdist}(x, \partial\Omega(t))| |\chi - \chi_\Omega| dx$$

$$+ \int_{\mathbb{R}^d} \text{sdist}(x, \partial\Omega(t)) \nabla |\chi|$$

IBP

$$= \int_{\mathbb{R}^d} \text{sdist}(x, \partial\Omega(t)) (\underbrace{\nabla - B \cdot \nu}_{\text{can be absorbed into dissipation of } \Sigma}) |\chi|$$

$$+ C \mathcal{F}$$

can be absorbed into dissipation of  $\Sigma$ .

$$\Rightarrow \frac{d}{dt} (\Sigma + \mathcal{F}) \leq \Sigma + \mathcal{F}.$$