Direct problem in differential Galois theory

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UVSQ & CNRS

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Joint work with M. Barkatou, T. Cluzeau and J.-A. Weil

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Why the Lie algebra is easier to calculate? Definition of reduced forms

Step 1 of the algorithm Differential modules

The algorithm Scheme of the algorithm

Characterization of reduced forms Aparicio-Compoint-Weil theorem

$$(k = \mathbb{C}(x), \partial = \frac{d}{dx})$$

 $\partial(Y) = AY$, with $A \in k^{n \times n}$

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 \exists a Picard-Vessiot extension K/k

i.e., a differential field extension $(K, \partial)/(k, \partial)$ s.t. $K^{\partial} = \mathbb{C}$ and $\exists U \in Gl_n(K)$, with $\partial(U) = AU$ and K = k(U).

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$$\rightsquigarrow \operatorname{\mathsf{Gal}}(A) = \operatorname{\mathsf{Aut}}^\partial(K/k) \hookrightarrow \operatorname{\mathsf{GL}}_n(\mathbb{C})$$

Important properties :

•
$$G := Gal(A)$$
 is an algebraic group $\Rightarrow \mathfrak{g} := Lie(G)$

• $\mathfrak{g} \subset \operatorname{End}(\mathbb{C}$ -vector space of solutions)

Direct problem

 \rightsquigarrow direct problem the differential Galois group

Compoint-Singer (1999), for reductive systems

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- \rightsquigarrow characterization of the <u>reduced forms</u> of $\partial(Y) = AY$
 - Aparicio-Compoint-Weil (2013), for completely reducible systems

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Dreyfus-Weil (in progress) for reductive systems

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→ algorithm to calculate the Lie algebra of the differential Galois group of an absolutely irreducible differential system Joint work with M. Barkatou, T. Cluzeau, J.-A. Weil

$$\partial Y = AY$$
, $A = (a_{i,j}) \in \mathbb{C}(x)^{n^2}$, group G , $\mathfrak{g} = Lie(G)$.

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Wei-Normann decomposition of $A = \sum_{h=1}^{r} \alpha_h M_h$

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$$\alpha_1, \ldots, \alpha_r$$
 is a \mathbb{C} -basis of $\sum_{i,j=1,\ldots,n} \mathbb{C}a_{i,j}$
▶ $M_1, \ldots, M_r \in \mathbb{C}^{n^2}$

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Lie(A) := the smallest alg. Lie algebra/ \mathbb{C} containing M_1, \ldots, M_r

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Proposition (Kolchin-Kovacic)

$$\mathfrak{g} \subset Lie(A)$$
 and
 $\exists P \in GL_n(\overline{\mathbb{C}(x)})$ s.t. $B = P'P^{-1} + PAP^{-1}$ and
 $\mathfrak{g} = Lie(B)$

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 $\partial Z = BZ$ is a <u>reduced form</u> of $\partial Y = AY$

 (\mathcal{M}, ∇) differential k-module of dimension n $\partial Y = AY$ associated differential system, with G and $\mathfrak{g} = Lie(G)$

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Hypotheses

1. (\mathcal{M}, ∇) absolutely irreducible $\Rightarrow \mathcal{M} \otimes_k \mathcal{M}^*$ is a direct sum of irreducibles

2. $\mathfrak{g} \subset \mathfrak{sl}_n(\mathbb{C}) \Rightarrow \mathfrak{g}$ is semi-simple

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The algorithm

- 1. Decomposing $\mathcal{M} \otimes_k \mathcal{M}^*$
- 2. Find a candidate $\mathfrak{g}^{guess} \subset \mathcal{M} \otimes_k \mathcal{M}^*$ for $\mathfrak{g} \otimes_{\mathbb{C}} \mathbb{C}(x)$

The algorithm



Characterization of reduced forms

 (\mathcal{M}, ∇) differential *k*-module of dimension *n* $\partial Y = AY$ associated differential system x_0 ordinary point for the system

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Characterization of reduced forms

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Théorème (Aparicio-Compoint-Weil 2013)

• $\partial Y = AY$ is a reduced form $\Leftrightarrow \forall$ Constr(\mathcal{M}) and $\forall \Phi$ rational solution of $\partial Y = Constr(A)Y$, Φ is a constant vector.

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Characterization of reduced forms

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Théorème (Aparicio-Compoint-Weil 2013)

- ∂Y = AY is a reduced form ⇔ ∀ Constr(M) and ∀Φ rational solution of ∂Y = Constr(A)Y, Φ is a constant vector.
- ► $\exists P \in GL_n(\bar{k}) \text{ s.t. } \partial Z = P[A]Z \text{ is a reduced form}$ $\forall \text{ Constr}(\mathcal{M}) \text{ and } \forall \Phi \text{ rational solution of}$ $\partial Y = \text{Constr}(A)Y, P \text{ sends } \Phi \text{ over } \Phi(x_0).$