Controlling General Polynomial Networks

N. Cuneo & J.-P. Eckmann
Your article is protected by copyright and all rights are held exclusively by Springer-Verlag Berlin Heidelberg. This e-offprint is for personal use only and shall not be self-archived in electronic repositories. If you wish to self-archive your article, please use the accepted manuscript version for posting on your own website. You may further deposit the accepted manuscript version in any repository, provided it is only made publicly available 12 months after official publication or later and provided acknowledgement is given to the original source of publication and a link is inserted to the published article on Springer’s website. The link must be accompanied by the following text: “The final publication is available at link.springer.com”.
Controlling General Polynomial Networks

N. Cuneo\textsuperscript{1}, J.-P. Eckmann\textsuperscript{1,2}

1 Département de Physique Théorique, Université de Genève, Geneva, Switzerland.
E-mail: noe.cuneo@unige.ch
2 Section de Mathématiques, Université de Genève, Geneva, Switzerland.
E-mail: jean-pierre.eckmann@unige.ch

Received: 8 January 2013 / Accepted: 3 August 2013
Published online: 9 March 2014 – © Springer-Verlag Berlin Heidelberg 2014

Abstract: We consider networks of massive particles connected by non-linear springs. Some particles interact with heat baths at different temperatures, which are modeled as stochastic driving forces. The structure of the network is arbitrary, but the motion of each particle is 1D. For polynomial interactions, we give sufficient conditions for Hörmander’s “bracket condition” to hold, which implies the uniqueness of the steady state (if it exists), as well as the controllability of the associated system in control theory. These conditions are constructive; they are formulated in terms of inequivalence of the forces (modulo translations) and/or conditions on the topology of the connections. We illustrate our results with examples, including “conducting chains” of variable cross-section. This then extends the results for a simple chain obtained in Eckmann et al. in (Commun Math Phys 201:657–697, 1999).

Contents
1. Introduction ........................................ 1255
2. The System ...................................... 1256
3. Strategy ........................................ 1259
4. The Neighbors of One Controllable Particle .... 1259
5. Controlling a Network ......................... 1266
6. Examples ...................................... 1269
7. Limitations and Extensions .................... 1270
8. Comparison with Other Commutator Techniques . 1273
A. Vandermonde Determinants ................. 1274
References ..................................... 1274

1. Introduction

We consider a network of interacting particles described by an undirected graph \( G = (V, E) \) with a set \( V \) of vertices and a set \( E \) of edges. Each vertex represents a particle,
and each edge represents a spring connecting two particles. We single out a set $V_*=\subset V$ of particles, each of which interacts with a heat bath. We address the question of when such a system has a unique stationary state. This question has been studied for several special cases: Starting from a linear chain [3,4], results have become more refined in terms of the relation between the spring potentials and the pinning potentials which tie the masses to the laboratory frame [1,11]. This problem is very delicate, as is apparent from the extensive study in [7] for the case of only 2 masses.

We provide conditions on the interaction potentials that imply Hörmander’s “bracket condition,” from which it follows that the semigroup associated to the process has a smoothing effect. This, together with some stability assumptions, implies the uniqueness of the stationary state. The existence is not discussed in this paper, but seems well understood in the case where the interaction potentials are stronger than the pinning potentials. This issue will be explained in a forthcoming paper [2].

Since the problem is known (see for example [6] and [10]) to be tightly related to the control problem where the stochastic driving forces are replaced with deterministic control forces, we shall use the terminology of control theory, and mention the implications of our results from the control-theoretic viewpoint.

We work with unit masses and interaction potentials that are polynomials of degree at least 3, and we say that two such potentials $V_1$ and $V_2$ have equivalent second derivative if there is a $\delta \in \mathbb{R}$ such that $V_1''(\cdot) = V_2''(\cdot + \delta)$.

We start with the set $V_*$ of particles that interact with heat baths, and are therefore controllable. One of our results (Corollary 5.6) is formulated as a condition for some of the particles in the set of first neighbors $\mathcal{N}(V_*)$ of $V_*$ to be also controllable. Basically, the condition is that these particles must be “inequivalent” in a sense that involves both the topology of their connections to $V_*$ and the corresponding interaction potentials. More precisely, a sufficient condition for a particle $v \in \mathcal{N}(V_*)$ to be controllable is that for each other particle $w \in \mathcal{N}(V_*)$ at least one of the two conditions holds:

(a) $v$ and $w$ are connected to $V_*$ in a topologically different way,

(b) there is a particle $c \in V_*$ such that the interaction potential between $c$ and $v$ and that between $c$ and $w$ have inequivalent second derivative.

It is then possible to use this condition recursively, taking control of more and more masses at each step (Theorem 5.7). If by doing so we can control all the masses in the graph, then Hörmander’s bracket condition holds.

In Sect. 6 we give examples of physically relevant networks whose controllability can be established using this method.

Our results imply in particular that connected graphs are controllable for “almost all” choices of the interaction potentials, provided that they are polynomials of degree at least 3 (Corollary 6.3).

2. The System

We define a Hamiltonian for the graph $G = (\mathcal{V}, \mathcal{E})$ as follows. Each particle $v \in \mathcal{V}$ has position $q_v \in \mathbb{R}$ and momentum $p_v \in \mathbb{R}$ and is “pinned down” by a potential $U_v(q_v)$. Throughout, we assume the masses being 1, for simplicity of notation. See Remark 4.20 on how to adapt the results when the masses are not all equal.

We denote each edge $e \in \mathcal{E}$ by $\{u, v\}$ (or equivalently $\{v, u\}$) where $u, v$ are the vertices adjacent to $e$. To each edge $e = \{u, v\}$, we associate an interaction potential $V_{uv}(q_u - q_v)$, or equivalently $V_{vu}(q_v - q_u)$ with

1 Due to the physical nature of the problem, we assume that the graph has no self-edge.
\[ V_{vu}(q_v - q_u) \equiv V_{uv}(q_u - q_v). \] (2.1)

Note that we do not require the potentials to be even functions; the condition (2.1) just makes sure that considering \( e = \{u, v\} \) or \( e = \{v, u\} \) leads to the same physical interaction, which is consistent with the fact that the edges are not oriented.

With the notation \( q = (q_v)_{v \in V} \) and \( p = (p_v)_{v \in V} \) the Hamiltonian is then

\[
H(q, p) = \sum_{v \in V} \left( \frac{p_v^2}{2} + U_v(q_v) \right) + \sum_{e \in E} V_e(\delta q_e),
\]

where it is understood that \( V_e(\delta q_e) \) denotes one of the two expressions in (2.1).

Finally, we make the following assumptions:

**Assumption 2.1.**
1. All functions are smooth.
2. The level sets of \( H \) are compact, i.e., for each \( K > 0 \) the set \( \{(q, p) \mid H(q, p) \leq K\} \) is compact.
3. The function \( \exp(-\beta H) \) is integrable for some \( \beta > 0 \).

Each particle \( v \in V \) is coupled to a heat bath at temperature \( T_v > 0 \) with coupling constant \( \gamma_v > 0 \). For convenience, we set \( \gamma_v = 0 \) when \( v \not\in V^* \). The model is then described by the system of stochastic differential equations

\[
\begin{align*}
dq_v &= p_v \, dt, \\
dp_v &= -U'_v(q_v) \, dt - \partial_{q_v} \left( \sum_{e \in E} V_e(\delta q_e) \right) \, dt - \gamma_v p_v \, dt + \sqrt{2T_v \gamma_v} \, dW_v(t),
\end{align*}
\] (2.2)

where the \( W_v \) are identical independent Wiener processes. The solutions to (2.2) form a Markov process. The generator of the associated semigroup is given by

\[
L \equiv X_0 + \sum_{v \in V^*} \gamma_v T_v \partial^2_{p_v},
\]

with

\[
X_0 \equiv - \sum_{v \in V^*} \gamma_v p_v \partial_{p_v} + \sum_{v \in V} \left( p_v \partial_{q_v} - U'_v(q_v) \partial_p \right) - \sum_{\{u, v\} \in E} V'_{uv}(q_u - q_v) \cdot (\partial_{p_u} - \partial_{p_v}).
\]

From now on, we assume that the interaction potentials \( V_e, e \in E \) are polynomials of degree at least 3. The condition on the degree means that we require throughout the presence of non-harmonicities. The fully-harmonic case has been described earlier [5], and the case where some but not all the potentials are harmonic is not covered here. We will show in a counter-example (Example 7.3) that the non-harmonicities are really essential for our results. We make no assumption about the pinning potentials \( U_v \); we do not require them to be polynomials, and some of them may be identically zero.

We work in the space \( \mathbb{R}^{2|V|} \) with coordinates \( x = (q, p) \). We identify the vector fields over \( \mathbb{R}^{2|V|} \) and the corresponding first-order differential operators in the usual way. This enables us to consider Lie algebras of vector fields over \( \mathbb{R}^{2|V|} \), where the Lie bracket \([\cdot, \cdot]\) is the usual commutator of two operators.

**Definition 2.2.** We define \( \mathcal{M} \) as the smallest Lie algebra that

1. contains \( \partial_{p_v} \) for all \( v \in V^* \),

2. Due to the identification mentioned above, we view here \( \partial_{p_v} \) as a constant vector field over \( \mathbb{R}^{2|V|} \).
(ii) is closed under the operation $[\cdot, X_0]$, 
(iii) is closed under multiplication by smooth scalar functions.

By the definition of a Lie algebra, $\mathcal{M}$ is closed under linear combinations and Lie brackets.

**Definition 2.3.** We say that a particle $v \in \mathcal{V}$ is controllable if we have $\partial_{q_v}, \partial_{p_v} \in \mathcal{M}$. We say that the network $\mathcal{G}$ is controllable if all the particles are controllable, i.e., if

$$\partial_{q_v}, \partial_{p_v} \in \mathcal{M} \quad \text{for all } v \in \mathcal{V}. \quad (2.3)$$

The aim of this paper is to give sufficient conditions on $\mathcal{G}$ and the interaction potentials, which guarantee that the network is controllable.

If the network is controllable in the sense $(2.3)$, then Hörmander’s condition $^3$ [8] holds: for all $x$, the vector fields $F \in \mathcal{M}$ evaluated at $x$ span all of $\mathbb{R}^{2|\mathcal{V}|}$, i.e.,

$$\{F(x) \mid F \in \mathcal{M}\} = \mathbb{R}^{2|\mathcal{V}|} \quad \text{for all } x \in \mathbb{R}^{2|\mathcal{V}|}. \quad (2.4)$$

Hörmander’s condition implies that the transition probabilities of the Markov process $(2.2)$ are smooth, and that so is any invariant measure (see for example [10, Corollary 7.2]). We now briefly mention two implications of these smoothness properties. Proposition 2.4 and Proposition 2.5 below can be deduced from arguments similar to those exposed in [6], and will be discussed in more detail in the forthcoming paper [2].

**Proposition 2.4.** Under Assumption 2.1, if $(2.4)$ holds, then the Markov process $(2.2)$ has at most one invariant probability measure.

The control-theoretic problem corresponding to $(2.2)$ is the system of ordinary differential equations

$$
\dot{q}_v = p_v,
\dot{p}_v = -U'_v(q_v) - \partial_{q_v} \left( \sum_{e \in \mathcal{E}} V_e(\delta q_e) \right) + (u_v(t) - \gamma_v p_v) \cdot 1_{v \in \mathcal{V}_s}, \quad (2.5)
$$

where for each $v \in \mathcal{V}_s$, $u_v : \mathbb{R} \to \mathbb{R}$ is a smooth control function (i.e., the stochastic driving forces have been replaced with deterministic functions).$^4$

**Proposition 2.5.** Under the hypotheses of Proposition 2.4, the system $(2.5)$ is controllable in the sense that for each $x^{(0)} = (q^{(0)}, p^{(0)})$ and $x^{(f)} = (q^{(f)}, p^{(f)})$, there are a time $T$ and some smooth controls $u_v$, $v \in \mathcal{V}_s$, such that the solution $x(t)$ of $(2.5)$ with $x(0) = x^{(0)}$ verifies $x(T) = x^{(f)}$.

In fact, $(2.4)$ is a well-known condition in control theory. See for example [9], which addresses the case of piecewise constant control functions. In particular, $(2.4)$ implies by [9, Theorem 3.3] that for every initial condition $x^{(0)}$ and each time $T > 0$, the set $A(x^{(0)}, T)$ of all points that are accessible at time $T$ (by choosing appropriate controls) is connected and full-dimensional.

$^3$ The condition $(2.4)$ is slightly different, but equivalent to the usual statement of Hörmander’s criterion. This can be checked easily. In particular, closing $\mathcal{M}$ under multiplication by smooth scalar functions does not alter the set in $(2.4)$, and will be very convenient.

$^4$ Whether or not we keep the dissipative terms $-\gamma_v p_v$ in $(2.5)$ makes no difference since they can always be absorbed into the control functions.
3. Strategy

We want to show that $\partial_{q_v}, \partial_{p_v} \in \mathcal{M}$ for all $v \in \mathcal{V}$. The next lemma shows that we only need to worry about the $\partial_{p_v}$.

**Lemma 3.1.** Let $A$ be a subset of $\mathcal{V}$.

If $\sum_{v \in A} \partial_{p_v} \in \mathcal{M}$ then $\sum_{v \in A} \partial_{q_v} \in \mathcal{M}$.

**Proof.** Assuming $\sum_{v \in A} \partial_{p_v} \in \mathcal{M}$, we find that

$$\left[ \sum_{v \in A} \partial_{p_v}, X_0 \right] = \sum_{v \in A} \partial_{q_v} - \sum_{v \in \mathcal{V}_* \cap A} \gamma_v \partial_{p_v} \quad (3.1)$$

is in $\mathcal{M}$. But since $\partial_{p_v} \in \mathcal{M}$ for all $v \in \mathcal{V}_*$, the linear structure of $\mathcal{M}$ implies $\sum_{v \in \mathcal{V}_* \cap A} \gamma_v \partial_{p_v} \in \mathcal{M}$. Adding this to the vector field in $(3.1)$ shows that $\sum_{v \in A} \partial_{q_v} \in \mathcal{M}$, as claimed. □

**Definition 3.2.** We say that a set $A \subseteq \mathcal{V}$ is jointly controllable if $\sum_{v \in A} \partial_{p_v}$ is in $\mathcal{M}$ (and therefore, also $\sum_{v \in A} \partial_{q_v}$ by Lemma 3.1).

Requiring all the particles in a set $A$ to be (individually) controllable is stronger than asking the set $A$ to be jointly controllable (indeed, if all the $\partial_{p_v}, v \in A$ are in $\mathcal{M}$, then so is their sum). We will obtain jointly controllable sets and then “refine” them until we control particles individually.

The strategy is as follows. In the next section, we start with a controllable particle $c$, and show that its first neighbors split into jointly controllable sets. Then, in Sect. 5, we consider several controllable particles, and basically intersect the jointly controllable sets obtained for each of them in order to control “new” particles individually. Finally, we iterate this procedure, taking control of more particles at each step, until we establish (under some conditions) the controllability of the whole network.

**Remark 3.3.** Observe in the following that our results neither involve the pinning potentials $U_v$ nor the coupling constants $\gamma_v$.

4. The Neighbors of One Controllable Particle

We consider in this section a particle $c \in \mathcal{V}$, and denote by $T^c$ the set of its first neighbors (the “targets”). The following notion of equivalence among polynomials enables us to split $T^c$ into equivalence classes.

**Definition 4.1.** Two polynomials $f$ and $g$ are called equivalent if there is a $\delta \in \mathbb{R}$ such that $f(\cdot) = g(\cdot + \delta)$.

**Definition 4.2.** We say that two particles $v, u \in T^c$ are equivalent (with respect to $c$) if the two polynomials $V''_v$ and $V''_u$ are equivalent.

Since this relation is symmetric and transitive, the set $T^c$ is naturally decomposed into a disjoint union of equivalence classes:

$$T^c = \bigcup_i T^c_i.$$
An explanation of why we use the second derivative of the potentials instead of the first one (i.e., the force) will be given in Example 7.2. The main result of this section is

**Theorem 4.3.** Assume that \( c \) is controllable. Then, each equivalence class \( T^c_i \) is jointly controllable, i.e.,

\[
\sum_{v \in T^c_i} \partial_{p_v} \in \mathcal{M} \quad \text{for all } i. 
\]  

(4.1)

Furthermore, there are constants \( \delta_{cv} \) such that for all \( i \),

\[
\sum_{v \in T^c_i} (q_c - q_v + \delta_{cv})\partial_{p_v} \in \mathcal{M}. 
\]  

(4.2)

The second part of the theorem will be used in the next section to intersect the equivalence classes \( T^c_i \) of several controllable particles \( c \). We will now prepare the proof of Theorem 4.3. We assume in the remainder of this section that \( c \) is controllable. And since \( c \) is fixed, we write \( T \) and \( T_i \) instead of \( T^c \) and \( T^c_i \).

**Lemma 4.4.** We have

\[
\sum_{v \in T} V''_{cv}(q_c - q_v)\partial_{p_v} \in \mathcal{M}. 
\]  

(4.3)

**Proof.** From Lemma 3.1 we conclude that \( \partial q_c \in \mathcal{M} \). Therefore, we find that

\[
[\partial q_c, X_0] = -U''(q_c)\partial_{p_c} - \sum_{v \in T} V''_{cv}(q_c - q_v) \cdot (\partial_{p_c} - \partial_{p_v})
\]

is in \( \mathcal{M} \). Now, since \( \partial_{p_c} \in \mathcal{M} \) and since \( \mathcal{M} \) is closed under multiplication by scalar functions, we can subtract all the contributions that are along \( \partial_{p_c} \) and obtain (4.3). \( \square \)

We need a bit of technology to deal with equivalent polynomials.

**Definition 4.5.** Let \( g(t) = \sum_{i=0}^{k} a_i t^i / i! \) be a polynomial of degree \( k \geq 1 \). If \( a_{k-1} = 0 \), we say that \( g \) is adjusted. As can be checked, the polynomial \( \tilde{g}(\cdot) \equiv g(\cdot - a_{k-1}/a_k) \) is always adjusted, and is referred to as the adjusted representation of \( g \).

Observe that a polynomial and its adjusted representation are by construction equivalent and have the same degree and the same leading coefficient. In fact, given a polynomial \( g \) of degree \( k \geq 1 \), \( \tilde{g} \) is the only polynomial equivalent to \( g \) that is adjusted. This adjusted representation will prove to be very useful thanks to the following obvious

**Lemma 4.6.** Two polynomials \( g \) and \( h \) of degree at least 1 are equivalent iff \( \tilde{g} = \tilde{h} \).

**Remark 4.7.** If all the interaction potentials are even, then all the \( V''_{cv} \) are automatically adjusted, and some parts of the following discussion can be simplified. We shift the argument of each \( V''_{cv} \) by a constant \( \delta_{cv} \) so that they are all adjusted. We let \( \tilde{f}_v \) be the adjusted representation of \( V''_{cv} \) and use the notation

\[
x_v = q_c - q_v + \delta_{cv}
\]

so that

\[
\tilde{f}_v(x_v) = V''_{cv}(q_c - q_v) \quad \text{for all } q_c, q_v \in \mathbb{R}.
\]
With this notation, (4.3) reads as
\[
\sum_{v \in T} \tilde{f}_v(x_v)\partial_{p_v} \in \mathcal{M}.
\] (4.4)

We will now mostly deal with “diagonal” vector fields, i.e., vector fields of the kind (4.4), where the component along $\partial_{p_v}$ depends only on $x_v$. When taking commutators, it is crucial to remember that $x_v$ is only a notation for $q_c - q_v + \delta_{cv}$.

**Remark 4.8.** By the definition of equivalence and Lemma 4.6, two particles $v, w \in T$ are equivalent iff $\tilde{f}_v$ and $\tilde{f}_w$ coincide.

**Lemma 4.9.** Consider some functions $g_v, v \in T$.
\[
\text{If } \sum_{v \in T} g_v(x_v)\partial_{p_v} \in \mathcal{M} \quad \text{then} \quad \sum_{v \in T} g'_v(x_v)\partial_{p_v} \in \mathcal{M}.
\] (4.5)

**Proof.** This is immediate by commuting with $\partial_{q_c}$ (which is in $\mathcal{M}$ by Lemma 3.1). □

We now introduce the main tool.

**Definition 4.10.** Given two vector fields $Y$ and $Z$, we define the double commutator $[Y : Z]$ by
\[
[Y : Z] \equiv [[X_0, Y], Z].
\]

Obviously, if the vector fields $Y$ and $Z$ are in $\mathcal{M}$, then so is $[Y : Z]$.

**Lemma 4.11.** Consider some functions $g_v, h_v, v \in T$. Then
\[
[\sum_{v \in T} g_v(x_v)\partial_{p_v} : \sum_{v' \in T} h_v'(x_{v'})\partial_{p_{v'}}] = \sum_{v \in T} (g_v h_v)'(x_v)\partial_{p_v}.
\] (4.6)

**Proof.** Observe first that (omitting the arguments $x_v$)
\[
[X_0, \sum_{v \in T} g_v \partial_{p_v}] = \sum_{v \in T} (p_c - p_v)g'_v \partial_{p_v} - \sum_{v \in T} g_v \partial_{q_v} + \sum_{v \in T \cap V^*} \gamma_v g_v \partial_{p_v}.
\]

Commuting with $\sum_{v' \in T} h_v'(x_{v'})\partial_{p_{v'}}$ gives the desired result. □

We will prove Theorem 4.3 starting from (4.4) and using only (4.5) and double commutators of the kind (4.6).

Let $d_v$ be the degree of $\tilde{f}_v$. Note that since the interaction potentials are of degree at least 3, we have $d_v \geq 1$. We define
\[
d \equiv \max_{v \in T} d_v \geq 1
\]
as the maximal degree of the adjusted polynomials $\tilde{f}_v$ with $v \in T$. We can then write
\[
\tilde{f}_v(x) = \sum_{j=0}^{d} b_{vj} x^j / j!,
\]
for some real coefficients $b_{vj}, j = 0, \ldots, d$, with
\[
b_{vj} = 0 \quad \text{if} \quad j > d_v \quad \text{and} \quad b_{vd_v - 1} = 0,
\]
for all $v \in T$. 
Definition 4.12. We define the set of particles \( v \in T \) corresponding to the maximal degree \( d \):

\[
\mathcal{D}^d \equiv \{ v \in T \mid d_v = d \}.
\]

For every \( \ell, 0 \leq \ell \leq d \), we define the set

\[
\mathcal{B}^d_\ell \equiv \{ b_{v,\ell} \mid v \in \mathcal{D}^d \}
\]

of distinct values taken by the coefficients of \( x_v^\ell / \ell! \) in \( \tilde{f}_v, v \in \mathcal{D}^d \).

We begin with a technical lemma. Observe how it is expressed in terms of the \( x_v \). In a sense, this shows that the \( x_v \) are really the “natural” variables for this problem. Thus, in addition to making the notion of equivalence trivial (Remark 4.8), working with adjusted representations will be very convenient from a technical point of view.

Lemma 4.13. The following hold:

(i) For each \( b \in \mathcal{B}^d_\ell \), we have

\[
\sum_{v \in \mathcal{D}^d : b_{v,\ell} = b} x_v \partial p_v \in \mathcal{M} \quad \text{and} \quad \sum_{v \in \mathcal{D}^d : b_{v,\ell} = b} \partial p_v \in \mathcal{M}.
\]

(ii) Furthermore,

\[
\sum_{v \in \mathcal{D}^d} x_v \partial p_v \in \mathcal{M} \quad \text{and} \quad \sum_{v \in \mathcal{D}^d} \partial p_v \in \mathcal{M}.
\]

(iii) Let \( \alpha_v, \beta_v, v \in \mathcal{D}^d \) be real constants. If \( d \geq 2 \), we have the two implications

\[
\text{if } \sum_{v \in \mathcal{D}^d} \alpha_v \partial p_v \in \mathcal{M}, \quad \text{then } \sum_{v \in \mathcal{D}^d} \alpha_v x_v \partial p_v \in \mathcal{M},
\]

\[
\text{if } \sum_{v \in \mathcal{D}^d} \alpha_v \partial p_v, \sum_{v \in \mathcal{D}^d} \beta_v \partial p_v \in \mathcal{M}, \quad \text{then } \sum_{v \in \mathcal{D}^d} \alpha_v \beta_v \partial p_v \in \mathcal{M}.
\]

Remark 4.14. Observe that the assumption \( d \geq 1 \) is crucial in the proof of (i). Requiring the \( \tilde{f}_v \) to be non-constant ensures that we can find non-trivial double commutators, which is the crux of our analysis. See Example 7.3 for what goes wrong for harmonic potentials.

Proof. (i). By (4.4) and using (4.5) recursively \( d - 1 \) times, we find that

\[
Y \equiv \sum_{v \in T} \left( \partial^{d-1} \tilde{f}_v \right) (x_v) \partial p_v = \sum_{v \in T} (b_{v,d-1} + b_{vd} x_v) \partial p_v
\]

is in \( \mathcal{M} \). But now, by (4.6),

\[
\left\lfloor Y : Y/2 \right\rfloor = \sum_{v \in T} b_{vd} (b_{v,d-1} + b_{vd} x_v) \partial p_v \in \mathcal{M}.
\]

Taking more double commutators with \( Y/2 \), we obtain for all \( r \geq 1 \):

\[
\sum_{v \in T} b_{vd}^r (b_{v,d-1} + b_{vd} x_v) \partial p_v \in \mathcal{M}.
\]
But the sum above is really only over $\mathcal{D}^d$ since $b_{vd} \neq 0$ only if $v \in \mathcal{D}^d$. Moreover, for these $v$, we have $b_{v,d-1} = 0$ since the polynomials are adjusted, so that for all $i \geq 2$,

$$\sum_{v \in \mathcal{D}^d} b_{vd}^i x_v \partial_{p_v} \in \mathcal{M}. \quad (4.11)$$

Let $b \in B_d^d$. Using Lemma A.1 with $s = 1$ and with the set of distinct and non-zero values $\{b_{vd} \mid v \in \mathcal{D}^d\} = B_d^d$ we find real numbers $r_1, r_2, \ldots, r_n$ (with $n = |B_d^d|$) such that $\sum_{i=1}^n r_i b_{vd}^{i+1}$ equals 1 if $b_{vd} = b$ and 0 when $b_{vd} \neq b$. Thus,

$$\sum_{i=1}^n r_i \sum_{v \in \mathcal{D}^d} b_{vd}^i x_v \partial_{p_v} = \sum_{v \in \mathcal{D}^d : b_{vd} = b} x_v \partial_{p_v}$$

is in $\mathcal{M}$ by (4.11). This together with (4.5) establishes the second inclusion of (4.7), so that we have shown (i).

The statement (ii) follows by summing (i) over all $b \in B_d^d$.

Proof of (iii). Let us assume that $d \geq 2$ and that $\sum_{v \in \mathcal{D}^d} \alpha_v \partial_{p_v} \in \mathcal{M}$. By (4.7), we have for each $b \in B_d^d$ that

$$\frac{1}{b} \sum_{v \in \mathcal{D}^d : b_{vd} = b} x_v \partial_{p_v} = \sum_{v \in \mathcal{D}^d : b_{vd} = b} \frac{x_v}{b_{vd}} \partial_{p_v} \in \mathcal{M}.$$  

Taking the double commutator with $\sum_{v \in \mathcal{D}^d} \alpha_v \partial_{p_v}$ and summing over all $b \in B_d^d$ shows that

$$U \equiv \sum_{v \in \mathcal{D}^d} \alpha_v \partial_{p_v} \in \mathcal{M}.$$  

Since we assume here $d \geq 2$, we have $Z \equiv \sum_{v \in \mathcal{T}} (\partial^{d-2} f_v) (x_v) \partial_{p_v} \in \mathcal{M}$. But then,

$$[U : Z] = \sum_{v \in \mathcal{T}} \frac{\alpha_v}{b_{vd}} \left( \partial^{d-1} f_v \right) (x_v) \partial_{p_v} = \sum_{v \in \mathcal{D}^d} \frac{\alpha_v}{b_{vd}} (b_{v,d-1} + b_{vd} x_v) \partial_{p_v}$$

is also in $\mathcal{M}$. Recalling that $b_{v,d-1} = 0$ for all $v \in \mathcal{D}^d$, we obtain (4.9). Finally (4.10) follows from (4.9) and the double commutator

$$[ \sum_{v \in \mathcal{D}^d} \alpha_v x_v \partial_{p_v} : \sum_{v \in \mathcal{D}^d} \beta_v \partial_{p_v} ] = \sum_{v \in \mathcal{D}^d} \alpha_v \beta_v \partial_{p_v}. $$

This completes the proof. □

With these preparations, we can now prove Theorem 4.3.

Proof (of Theorem 4.3). We distinguish the cases $d = 1$ and $d \geq 2$.

Case $d = 1$: This case is easy. Since all the $f_v$ have degree 1, we have that $f_v(x_v) = b_{v1} x_v$ for all $v \in \mathcal{T}$, with $b_{v1} \neq 0$. Consequently, the sets $\mathcal{T}_i$ consist of those $v$ which have the same $b_{v1}$ (see Remark 4.8). Thus, we have by (4.7) that for each $\mathcal{T}_i$:

$$\sum_{v \in \mathcal{T}_i} \partial_{p_v} \in \mathcal{M} \quad \text{and} \quad \sum_{v \in \mathcal{T}_i} x_v \partial_{p_v} \in \mathcal{M} \quad \text{(if } d = 1). \quad (4.12)$$

This shows that the conclusion of Theorem 4.3 holds when $d = 1$. 
Case $d \geq 2$: In this case, (4.7) is not enough. First, (4.7) says nothing about the masses $v \in T \setminus \mathcal{D}^d$, for which $b_{vd} = 0$. And second, (4.7) provides us with no way to “split” the $\partial p_v$ corresponding to a common (non-zero) value $b$ of $b_{vd}$, even though the corresponding $v$ might be inequivalent due to some $b_{vk}$ with $k < d$. To fully make use of these coefficients, we must develop some more advanced machinery.

**Definition 4.15.** We denote by $\mathcal{P}_d$ the vector space of real polynomials in one variable of degree at most $d$. We consider the operator $G : \mathcal{P}_d \rightarrow \mathcal{P}_d$ defined by

$$(Gv)(x) \equiv (x \cdot v(x))',$$

and we introduce the set of operators

$$\mathcal{F} \equiv \text{span}\{G, G^2, \ldots, G^{d+1}\}.$$  

Observe that by (4.4) and (4.8) we have

$$\sum_{v \in T} \tilde{f}_v(x_v) \partial p_v : \sum_{v \in \mathcal{D}^d} x_v \partial p_v \implies \sum_{v \in \mathcal{D}^d} (G \tilde{f}_v)(x_v) \partial p_v \in \mathcal{M}. $$

Note that we obtain a sum over $\mathcal{D}^d$ only. By taking more double commutators with $\sum_{v \in \mathcal{D}^d} x_v \partial p_v$, we find that $\sum_{v \in \mathcal{D}^d} (G^k \tilde{f}_v)(x_v) \partial p_v$ is in $\mathcal{M}$ for all $k \geq 1$. Thus, by the linear structure of $\mathcal{M}$, we obtain

**Lemma 4.16.** For all $P \in \mathcal{F}$, we have

$$\sum_{v \in \mathcal{D}^d} (P \tilde{f}_v)(x_v) \partial p_v \in \mathcal{M}. $$

It is crucial to understand that it is the *same* operator $P$ that is applied simultaneously to all the components, and that the components in $T \setminus \mathcal{D}^d$ are “projected out.”

We now show that some very useful operators are in $\mathcal{F}$.

**Proposition 4.17.** The following hold:

(i) The projector

$$S_\ell : \mathcal{P}_d \rightarrow \mathcal{P}_d, \quad \sum_{i=0}^d b_i x^i / i! \mapsto b_\ell x^\ell / \ell!$$

belongs to $\mathcal{F}$ for all $\ell = 0, \ldots, d$.

(ii) The identity operator $1$ acting on $\mathcal{P}_d$ is in $\mathcal{F}$.

**Proof.** Consider the basis $B = (e_0, e_1, \ldots, e_d)$ of $\mathcal{P}_d$ where $e_j(x) = x^j / j!$. Observe that for all $j \geq 0$ we have $Ge_j = (j + 1)e_j$, so that $G$ is diagonal in the basis $B$. Thus, $G^k$ is represented by the matrix $\text{diag}(1^k, 2^k, \ldots, (d + 1)^k)$ for all $k \geq 1$. Consequently, for each $\ell \in \{0, \ldots, d\}$, there is by Lemma A.1 with $s = 0$ a linear combination of $G, G^2, \ldots, G^{d+1}$ that is equal to $S_\ell$. This proves (i). Moreover, we have that $\sum_{\ell=0}^d S_\ell = 1$, so that the proof of (ii) is complete. □

**Lemma 4.18.** For all $\ell = 0, \ldots, d$, and for each $b \in B_\ell^d = \{b_{v\ell} \mid v \in \mathcal{D}^d\}$ we have

$$\sum_{v \in \mathcal{D}^d : b_{v\ell} = b} \partial p_v \in \mathcal{M}. \quad (4.13)$$
Proof. Let $\ell \in \{0, 1, \ldots, d\}$. Using Lemma 4.16 and Proposition 4.17(i) we find that $\sum_{v \in D^d} (b_v x^\ell / \ell!) \partial_p v$ is in $\mathcal{M}$. Using (4.5) repeatedly, we find that $\sum_{v \in D^d} b_v x^\ell / \ell! \partial_p v$ is in $\mathcal{M}$. Thus, by (4.10),

$$\sum_{v \in D^d} b_v x^\ell / \ell! \partial_p v \in \mathcal{M} \quad \text{for all } i \geq 1.$$  

Then, applying Lemma A.1 to the set $B^d_{\ell} \setminus \{0\}$ and with $s = 0$, we conclude that

$$\sum_{v \in D^d} b_v x^\ell \partial_p v \in \mathcal{M}.$$  

If $0 \notin B^d_{\ell}$, we are done. Else, we obtain that (4.13) holds also for $b = 0$ by summing the vector field (4.14) over all $b \in B^d_{\ell} \setminus \{0\}$ and subtracting the result from $\sum_{v \in D^d} \partial_p v$ [which is in $\mathcal{M}$ by (4.8)]. This completes the proof.  

Remember that by Remark 4.8, a given equivalence class $T_i$ is either a subset of $D^d$ or completely disjoint from it.

Lemma 4.19. Let $T_i$ be an equivalence class such that $T_i \subset D^d$. Then

$$\sum_{v \in T_i} \partial_p v \in \mathcal{M}, \quad \text{and} \quad \sum_{v \in T_i} x^v \partial_p v \in \mathcal{M}. \quad (4.15)$$

Proof. All the polynomials $\tilde{f}_v, v \in T_i$ are equal. Thus, there are coefficients $c_\ell \in B^d_{\ell}$, $\ell = 0, 1, \ldots, d$ such that

$$T_i = \bigcap_{\ell=0}^d \{v \in D^d \mid b_v x^\ell = c_\ell\}. \quad (4.16)$$

By Lemma 4.18, we have for all $\ell = 0, \ldots, d$ that

$$\sum_{v \in D^d : b_v x^\ell = c_\ell} \partial_p v \in \mathcal{M}. \quad (4.17)$$

Now observe that whenever two sets $B, B' \subset D^d$ are such that $\sum_{v \in B} \partial_p v \in \mathcal{M}$ and $\sum_{v \in B'} \partial_p v \in \mathcal{M}$, we have by (4.10) that $\sum_{v \in B \cap B'} \partial_p v \in \mathcal{M}$. Applying this recursively to the intersection in (4.16) and using (4.17) shows that $\sum_{v \in T_i} \partial_p v \in \mathcal{M}$. Using now (4.9) implies that $\sum_{v \in T_i} x^v \partial_p v \in \mathcal{M}$, which completes the proof.  

With these tools, we are now ready to complete the proof of Theorem 4.3 (for the case $d \geq 2$). By Lemma 4.19, we are done if $D^d = T$ (i.e., if all the $\tilde{f}_v, v \in T$ have degree $d$). If this is not the case, we proceed as follows.

Observe that Lemma 4.16 and Proposition 4.17(ii) imply that $\sum_{v \in D^d} \tilde{f}_v(x_v) \partial_p v$ is in $\mathcal{M}$. Subtracting this from (4.4) shows that

$$\sum_{v \in T \setminus D^d} \tilde{f}_v(x_v) \partial_p v \in \mathcal{M}.$$  

Thus, we can start the above procedure again with this new “smaller” vector field, each component being a polynomial of degree at most

$$d' \equiv \max_{v \in T \setminus D^d} d_v,$$
with obviously \( d' < d \). Defining then \( D^{d'} = \{ v \in T \mid d_v = d' \} \), we get as in Lemma 4.19 that (4.15) holds for all \( T_i \subset D^{d'} \). We then proceed like this inductively, dealing at each step with the components of highest degree and “removing” them, until all the remaining components have the same degree \( d^- \) (which is equal to \( \min_{v \in T} d_v \)). If \( d^- \geq 2 \) we obtain again as in Lemma 4.19 that (4.15) holds for all \( T_i \subset D^{d^-} \). And if \( d^- = 1 \), the conclusion follows from (4.12). Thus, (4.15) holds for every equivalence class \( T_i \), regardless of the degree of the polynomials involved. The proof of Theorem 4.3 is complete.

\[ \square \]

**Remark 4.20.** Our method also covers the case where each particle \( v \in V \) can have an arbitrary positive mass \( m_v \). The proofs work the same way, if we replace the functions \( \tilde{f}_v \) with \( \tilde{f}_v = V''_{cv}(x_v)/(m_cm_v) \). Thus, if for example all the \( V''_{cv}, v \in T \) are the same, but all the particles in \( T \) have distinct masses, then all the new \( \tilde{f}_v \) are different, and the particles in \( T \) belong each to a separate \( T_i \).

## 5. Controlling a Network

We now show how Theorem 4.3 can be used recursively to control a large class of networks. The idea is very simple: at each step of the recursion, we apply Theorem 4.3 to a controllable particle (or a set of such) in order to show that some neighboring vertices are also controllable. Starting this procedure with the particles in \( V_* \) (which are controllable by the definition of \( M \)), we obtain under certain conditions that the whole network is controllable.

In order to make the distinction clear, we will say that a particle \( c \) is a **controller** if it is controllable and if we intend to use it as a starting point to control other particles.

**Definition 5.1.** Let \( J \) be the collection of jointly controllable sets (i.e., of sets \( A \subset V \) such that \( \sum_{v \in A} \partial p_v \in M \), and therefore also \( \sum_{v \in A} \partial q_v \) by Lemma 3.1).

Obviously, a particle \( v \) is controllable iff \( \{ v \} \in J \). The next lemma shows what we “gain” in \( J \) when we apply Theorem 4.3 to a controller \( c \). Remember that the set \( T^c \) of first neighbors of \( c \) is partitioned into equivalence classes \( T^c_i \), as discussed in Sect. 4.

**Lemma 5.2.** Let \( c \in V \) be a controller. Then,

(i) for all \( i \),

\[ T^c_i \in J, \]

(ii) for all \( i \) and for all \( A \in J \) the sets

\[ A \cap T^c_i, \quad A \setminus T^c_i \quad \text{and} \quad T^c_i \setminus A \quad (5.1) \]

are in \( J \).

We illustrate some possibilities in Fig. 1.

**Proof.** (i). This is an immediate consequence of (4.1) and the definition of \( J \).

(ii). We consider an equivalence class \( T^c_i \) and a set \( A \in J \). By (4.2) we find that

\[
\left[ \sum_{v \in T^c_i} (q_c - q_v + \delta_{cv}) \partial p_v, \sum_{v \in A} \partial q_v \right] = \sum_{v \in A \cap T^c_i} \partial p_v - 1_{c \in A} \cdot \sum_{v \in T^c_i} \partial p_v
\]
Fig. 1. a A controller $c$ and a few sets in $\mathcal{J}$, shown as ovals. b The equivalence classes $T^c_i$ are shown as rectangles. (Only the edges incident to $c$ are shown.) c New sets “appear” in $\mathcal{J}$. In particular, $c'$ and $c''$ are controllable.

is in $\mathcal{M}$. By the linear structure of $\mathcal{M}$ and since $\sum_{v \in T^c_i} \partial p_v$ is in $\mathcal{M}$ by (4.1), we can discard the second term and we find $\sum_{v \in A \cap T^c_i} \partial p_v \in \mathcal{M}$. This proves that $A \cap T^c_i$ is in $\mathcal{J}$. Then, subtracting $\sum_{v \in A \cap T^c_i} \partial p_v$ from $\sum_{v \in A} \partial p_v$ (resp. from $\sum_{v \in T^c_i} \partial p_v$) shows that $\sum_{v \in A \setminus T^c_i} \partial p_v$ (resp. $\sum_{v \in T^c_i \setminus A} \partial p_v$) is in $\mathcal{M}$, which completes the proof of (ii). \hfill $\square$

We can now give an algorithm that applies Lemma 5.2 recursively, and that can be used to show that a large variety of networks is controllable.

**Proposition 5.3.** Consider the following algorithm that builds step by step a collection of sets $W \subset \mathcal{J}$ and a list of controllable particles $K$.

Start with $W = \{\{v\} \mid v \in \mathcal{V}_s\}$ and put (in any order) the vertices of $\mathcal{V}_s$ in $K$.

1. Take the first unused controller $c \in K$.
2. Add each equivalence class $T^c_i$ to $W$.
3. For each $T^c_i$ and each $A \in W$ add the sets of (5.1) to $W$.
4. If in 2. or 3. new singletons appear in $W$, add the corresponding vertices (in any order) at the end of $K$.
5. Consider $c$ as used. If there is an unused controller in $K$, start again at 1. Else, stop.

We have the following result: if in the end $K$ contains all the vertices of $\mathcal{V}$, then the network is controllable.

**Proof.** By Lemma 5.2, the collection $W$ remains at each step a subset of $\mathcal{J}$, and $K$ contains only controllers. Thus, the result holds by construction. \hfill $\square$

The algorithm stops after at most $|\mathcal{V}|$ iterations, and one can show that the result does not depend on the order in which we use the controllers. This algorithm is probably the easiest to implement, but does not give much insight into what really makes a network controllable with our criteria. For this reason, we now formulate a similar result in terms of equivalence with respect to a set of controllers, which underlines the role of the “cooperation” of several controllers.

**Definition 5.4.** We consider a set $C$ of controllers and denote by $\mathcal{N}(C)$ the set of first neighbors of $C$ that are not themselves in $C$. We say that two particles $v, w \in \mathcal{N}(C)$
Fig. 2. Illustration of Definition 5.4. We assume that all the springs are identical, except for the edge \( c_1, v_1 \). The particles \( v_1, \ldots, v_6 \) form 4 sets of \( C \)-siblings, with \( C = \{ c_1, c_2, c_3 \} \). The one containing \( v_1 \) and \( v_2 \) is further split into two \( C \)-equivalence classes, since \( v_1 \) and \( v_2 \) are by assumption inequivalent with respect to \( c_1 \).

Fig. 3. Illustration of the proof of Proposition 5.5 for identical springs. We consider the \( C \)-equivalence class \( U = \{ v_1, v_2 \} \), where \( C \) contains \( c_1, c_2, c_3^* \) and possibly other particles (not shown) that are not linked to \( v_1, v_2 \). With the notation of the proof, we have \( S_1 = \{ w, v_1, v_2, v_1^* \} \) and \( S_2 = \{ v_1, v_2, v_1^* \} \) so that \( \hat{U} = S_1 \cap S_2 = \{ v_1, v_2, v_1^* \} \). Since \( v_1^* \) belongs to \( S_1^* = \{ w, v_1^* \} \), we find \( \hat{U} \setminus S_1^* = U \).

are \( C \)-siblings if \( v \) and \( w \) are connected to \( C \) in exactly the same way, i.e., if for every \( c \in C \) the edges \( \{ c, v \} \) and \( \{ c, w \} \) are either both present or both absent.

Moreover, we say that \( v \) and \( w \) are \( C \)-equivalent if they are \( C \)-siblings, and if in addition, for each \( c \in C \) that is linked to \( v \) and \( w \), we have that \( v \) and \( w \) are equivalent with respect to \( c \) [i.e., there is a \( \delta \in \mathbb{R} \) such that \( V''_{cv}(\cdot) = V''_{cw}(\cdot + \delta) \)].

The \( C \)-equivalence classes form a refinement of the sets of \( C \)-siblings, see Fig. 2.

**Proposition 5.5.** Let \( C \) be a set of controllers. Then, for each \( C \)-equivalence class \( U \subset \mathcal{N}(C) \), we have \( U \in \mathcal{J} \).

**Proof.** See Fig. 3. Let \( U = \{ v_1, \ldots, v_n \} \subset \mathcal{N}(C) \) be a \( C \)-equivalence class. We denote by \( c_1, \ldots, c_k \) the controllers in \( C \) that are linked to \( v_1 \), and therefore also to \( v_2, \ldots, v_n \), since the elements of \( U \) are \( C \)-siblings. For each \( j \in \{ 1, \ldots, k \} \), there is a \( T_i^{c_j} \) with \( v_1, \ldots, v_n \in T_i^{c_j} \), and we define \( S_j = T_i^{c_j} \setminus C \). We consider the set

\[
\hat{U} = \bigcap_{j=1}^k S_j.
\]
Clearly, $U \subset \hat{U}$, and $\hat{U} \in J$ by Lemma 5.2. We have $\hat{U} = \{v_1, \ldots, v_n, v_1^*, \ldots, v^*_r\}$, where the $v_j^*$ are those particles that are equivalent to $v_1, \ldots, v_n$ from the point of view of $c_1, \ldots, c_k$, but that are also connected to some controller(s) in $C \setminus \{c_1, \ldots, c_k\}$. In particular, for each $j \in \{1, \ldots, r\}$, there is a $c_j^* \in C \setminus \{c_1, \ldots, c_k\}$ and an $i$ such that $v_j^*$ is in $S_j^* \equiv T_i^{c_j^*}$. By construction, $S_j^* \cap U = \emptyset$. Thus,

$$\hat{U} \setminus \bigcup_{j=1}^r S_j^* = U.$$ 

Starting from $\hat{U} \in J$ and removing one by one the $S_j^*$, we find by Lemma 5.2(ii) that $U$ is indeed in $J$, as we claim. \(\square\)

An immediate consequence is

**Corollary 5.6.** Let $C$ be a set of controllers. If a vertex $v \in N(C)$ is alone in its $C$-equivalence class, then it is controllable.

Applying this recursively, we obtain

**Theorem 5.7.** We start with $C_0 \equiv V_*$. For each $k \geq 0$, let

$$C_{k+1} \equiv C_k \cup \{v \in N(C_k) \mid \text{no other vertex in } N(C_k) \text{ is } C_k \text{-equivalent to } v\}.$$ 

Then, if $C_k = V$ for some $k \geq 0$, the network is controllable.

**Proof.** By Corollary 5.6 we have that each $C_k$ contains only controllers (remember also that $V_*$ contains only controllers by the definition of $M$). Thus if $C_k = V$ for some $k \geq 0$ we find that all vertices are controllers, which is what we claim. \(\square\)

### 6. Examples

In this section we illustrate by several examples the range of our controllability criteria.

**Example 6.1.** A single controller $c$ can control several particles if the interaction potentials between $c$ and its neighbors have pairwise inequivalent second derivative. See Fig. 4.

The example above does not use the topology of the network (i.e., the notion of siblings), but only the inequivalence due to the second derivative of the potentials. We have the following immediate generalization, which we formulate as

**Theorem 6.2.** Assume that $G$ is connected, that $V_*$ is not empty, and that for each $v \in V$, the first neighbors of $v$ are all pairwise inequivalent with respect to $v$ (i.e., no two distinct neighbors $u, w$ of $v$ are such that $V''_{vu}(\cdot) = V''_{vw}(\cdot + \delta)$ for some constant $\delta \in \mathbb{R}$). Then, the network is controllable.

**Proof.** We use Theorem 5.7. Observe that under these assumptions, we have at each step $C_{k+1} = C_k \cup N(C_k)$. Thus, since the network is connected, there is indeed a $k \geq 0$ such that $C_k = V$. \(\square\)

One can restate Theorem 6.2 as a genericity condition:
Fig. 4. If no two springs are equivalent, the \( v_i \) are controllable. Springs from the \( v_i \) to other particles or from one \( v_i \) to another may exist but are not shown. They do not change the conclusion.

Fig. 5. A one-dimensional chain

**Corollary 6.3.** Assume that \( \mathcal{G} \) is connected, that \( \mathcal{V}_* \) is not empty, and that for each \( e \in \mathcal{E} \) the degree of the polynomial \( V_e \) is fixed (and is at least 3). Then, \( \mathcal{G} \) is almost surely controllable if we pick the coefficients of each \( V_e \) at random according to a probability law that is absolutely continuous w.r.t. Lebesgue.

**Example 6.4.** The 1D chain (shown in Fig. 5) is controllable. Our theory applies when the interactions are polynomials of degree at least 3; for a somewhat different variant, see [4]. To apply our criteria, we start with \( C = \{c\} \). Clearly, \( v_1 \) is alone in its \( C \)-equivalence class, and is therefore controllable by Corollary 5.6. We then take \( C' = \{c, v_1\} \). Since \( v_2 \) is alone in its \( C' \)-equivalence class, it is also controllable. Continuing like this, we find that the whole chain is controllable.

Observe that the chain described in the example above is controllable whether some pairs of springs are equivalent or not. There are in fact many networks that are controllable thanks to their topology alone, regardless of the potentials. In particular, we have

**Example 6.5 (Physically relevant networks).** We consider the network in Fig. 6a and we start with \( C = \{c_1, \ldots, c_4\} \) (i.e., we assume that the vertices in the first column are controllers). Since no two vertices in the second column are \( C \)-siblings, they each belong to a distinct \( C \)-equivalence class, and therefore by Corollary 5.6 they are controllable (regardless of the potentials). Let us now denote by \( C' \) the set of all vertices in the first two columns, which are controllable as we have just seen. Repeating the argument above, we obtain that the vertices in the third column are controllable. Continuing like this, we gain control of the whole network. In the same way, one also easily obtains that the networks in Fig. 6b–d are controllable thanks to their topology alone.

**7. Limitations and Extensions**

Our theory is local in the sense that the central tool (Theorem 4.3) involves only a controller and its first neighbors. When we “walk through the graph,” starting from \( \mathcal{V}_* \) and taking at each step control of more particles, we only look at the interaction...
Fig. 6. Four networks that are controllable by their topology alone, regardless of the potentials (as long as they are polynomials of degree at least 3)

Fig. 7. The network used in Example 7.1. If $V_{c v_3}$ is equivalent to $V_{c v_1}$ our theory does not allow to conclude, but the network might still be controllable.

potentials that involve the particles we already control and their first neighbors. We never look “farther” in the graph. This makes our criteria quite easy to apply, but this is also the main limitation of our theory, as illustrated in

Example 7.1. We consider the network shown in Fig. 7, where $c$ is a controller. If $V''_{c v_1}$ and $V''_{c v_3}$ are equivalent, then our theory fails to say anything about the controllability of the network. In order to draw any conclusion, one has to look at “what comes next” in the network. Of course, if the lower branch is an exact copy of the upper one (i.e., if the interaction and pinning potentials are the same), then the network is truly uncontrollable, and this is obvious for symmetry reasons. However, without such an “unfortunate” symmetry, the network may still be controllable. Indeed, by the study above, we know that the vector field $Y \equiv \partial_{v_1} + \partial_{v_3}$ is in $M$. By commuting with $X_0$ and subtracting...
some contributions already in $\mathcal{M}$, one easily obtains that the vector field

$$U''_{v1} \partial_{p_{v1}} + U''_{v3} \partial_{p_{v3}} + V''_{v1v2} \cdot (\partial_{p_{v1}} - \partial_{p_{v2}}) + V''_{v3v4} \cdot (\partial_{p_{v3}} - \partial_{p_{v4}})$$

is in $\mathcal{M}$. Observe that now the pinning potentials $U_{v1}$ and $U_{v3}$ as well as the interaction potentials $V_{v1v2}$ and $V_{v3v4}$ come into play. Taking first commutators with $Y$ and then taking double commutators among the obtained vector fields, one obtains further vector fields of the form

$$\sum_{i=1}^{4} g_i(q_{v1}, q_{v2}, q_{v3}, q_{v4}) \partial_{p_{v1}}$$

where the $g_i$ involve derivatives and products of the potentials mentioned above. In many cases, these are enough to prove that the network in Fig. 7 is controllable, even though our theory fails to say so.

One question that might arise is: why does only the second derivative of the interaction potentials enter the theory? The next example shows that this issue is related to the notion of locality mentioned above.

**Example 7.2.** We consider the network in Fig. 8, where $c$ is a controller. We study the case where

$$V_{cv}(q_c - q_v) = (q_c - q_v)^4,$$
$$U_{v}(q_v) = q_v^6,$$
$$V_{cw}(q_c - q_w) = (q_c - q_w)^4 + a \cdot (q_c - q_w),$$
$$U_{w}(q_w) = q_w^6 + b \cdot q_w,$$

for some constants $a$ and $b$. The terms in $a$ and $b$ act as constant forces on $c$ and $w$. Since $V''_{cv} \sim V''_{cw}$, the particles $v$ and $w$ are equivalent with respect to $c$ by our definition. Thus, our theory fails to say anything. We seem to be missing the fact that when $a \neq 0$, the particles $v$ and $w$ can be told apart due to the first derivative of the potentials. However, having $a \neq 0$ is not enough; the controllability of the network also depends on $b$. Indeed, if $a = b$, the vector field $X_0$ is symmetric in $v$ and $w$, and therefore the network is genuinely uncontrollable. If now $a \neq b$, we have checked, by following a different strategy of taking commutators, that the network is controllable. Consequently, when two potentials have equivalent second derivative, but inequivalent first derivative, no conclusion can be drawn in general without knowing more about the network (here, it is one of the pinning potentials, but in more complex situations, it can be some subsequent springs).

Our theory applies only to strictly anharmonic systems, since we assume that the interaction potentials have degree at least 3. The next example shows what can go wrong if we drop this assumption. Again, this is related to the locality of our criteria.

**Example 7.3.** We consider the harmonic system shown in Fig. 9. The vertex $c$ is a controller, and all the pinning potentials are equal and harmonic, i.e., of the form $\lambda x^2/2$. The interaction potentials are also harmonic. The spring $\{c, v_1\}$ has coupling constant $2$, the springs $\{c, v_2\}$ and $\{v_2, v_3\}$ have coupling constant $1$ and the spring $\{v_3, v_4\}$ has
coupling \( k > 0 \). Since \( V''_{c v_1} \equiv 2 \) and \( V''_{c v_2} \equiv 1 \), the particles \( v_1 \) and \( v_2 \) are inequivalent with respect to \( c \). Yet, this is not enough to obtain that they are controllable (unlike in the strictly anharmonic case covered by our theory). With standard methods for harmonic systems, it can be shown that the network is controllable iff \( k \neq 2 \). When \( k = 2 \), one of the eigenmodes decouples from the controller \( c \), and no particle except \( c \) is controllable. Thus, one cannot obtain that \( v_1 \) and \( v_2 \) are controllable without knowing more about the potentials that come farther in the graph.

**Remark 7.4.** As presented here, our method only works when the motion of each particle is 1D. To some extent, our results can be generalized to higher dimensions. For example, one can check that in any dimension \( r \geq 1 \), the network of Fig. 4 with potentials \( V_k(x_k) = a_k \left( x_{k,1}^2 + \cdots + x_{k,r}^2 \right)^2, k = 1, \ldots, n \), is controllable when the \( a_k \) are all distinct and non-zero. But for generic polynomial potentials, the situation is more complicated: taking multiple commutators does not always lead to tractable expressions [in particular, we do not have the nice form (4.6) for double commutators anymore]. Further research is needed to find an adequate method for general higher dimensional problems. For some networks with special topology (such as the one in Fig. 6a but not the ones in Fig. 6b–d), simple conditions can be found for controllability, even for non-polynomial potentials (see [2]).

## 8. Comparison with Other Commutator Techniques

It is perhaps useful to compare the techniques used in this paper to those used elsewhere: To unify notation, we consider the hypoellipticity problem in the classical form

\[
L = X_0 + \sum_{i>0} X_i^2.
\]

In [4], the authors considered a chain, so that \( V_* \) is just the first and the last particle in the chain. Starting with \( \partial_{p_1} \) (the left end of the chain) one then forms (with simplified notation, which glosses over details which can be found in that paper)

\[
\partial_{q_1} = [\partial_{p_1}, X_0], \quad \partial_{p_2} = (M_{1,2})^{-1}[\partial_{q_1}, X_0], \quad \partial_{q_2} = [\partial_{p_2}, X_0],
\]

and so on, going through the chain. Here, the particles are allowed to move in several dimensions, and \( M_{j,j+1} \) is basically the Hessian matrix of \( V_{j,j+1} \). This technique requires that \( M_{j,j+1} \) be invertible, which implies some restrictions on the potentials.

Villani [12] uses another sequence of commutators:

\[
C_0 = \{X_i\}_{i>0}, \quad C_{j+1} = [C_j, X_0] + \text{remainder}_j.
\]
With this superficial notation, the current paper uses again a walk through the network, but the basic step involves double commutators of the form

\[ [Z_1 : Z_2] \]

with \( Z_i \) typically of the form \( \sum g_v(x_v)\partial_{p_v} \), where we use abundantly that the \( V_e \) are polynomials. This allows for the “fanning out” of Fig. 4 and is at the basis of our ability to control very general networks. In particular, this shows that networks with variable cross-section can be controlled.

Acknowledgements. We thank Ch. Boeckle, J. Guillod, T. Yarmola, and M. Younan for discussions and careful reading of the manuscript. This research was supported by an ERC advanced grant “Bridges” and the Fonds National Suisse.

A. Vandermonde Determinants

Lemma A.1. Let \( c_1, \ldots, c_n \in \mathbb{R} \) be distinct and non-zero, and let \( s \geq 0 \). Then, for all \( k \in \{1, \ldots, n\} \) there are constants \( r_1, \ldots, r_n \in \mathbb{R} \) such that for all \( j = 1, \ldots, n \),

\[
\sum_{i=1}^n r_i c_j^{i+s} = \delta_{jk}.
\]

Proof. We have that the Vandermonde determinant

\[
\begin{vmatrix}
1 & c_1 & c_1^2 & \cdots & c_1^n \\
1 & c_2 & c_2^2 & \cdots & c_2^n \\
\vdots & \vdots & \vdots & \ddots & \vdots \\
1 & c_n & c_n^2 & \cdots & c_n^n \\
\end{vmatrix}
= \prod_{i=1}^n \left( \sum_{j=i+1}^n (c_j - c_i) \right) = \prod_{i=1}^n c_i^{s+1} \prod_{j=i+1}^n (c_j - c_i)
\]

is non-zero under our assumptions. Thus, the columns of this matrix form a basis of \( \mathbb{R}^n \), which proves the lemma. \( \square \)

References

1. Eckmann, J.-P., Hairer, M.: Non-equilibrium statistical mechanics of strongly anharmonic chains of oscillators. Commun. Math. Phys. 212, 105–164 (2000)
2. Eckmann, J.-P., Hairer, M., Rey-Bellet L.: Non-equilibrium steady states for networks of springs. In preparation
3. Eckmann, J.-P., Pillet, C.-A., Rey-Bellet, L.: Entropy production in nonlinear, thermally driven Hamiltonian systems. J. Stat. Phys. 95, 305–331 (1999)
4. Eckmann, J.-P., Pillet, C.-A., Rey-Bellet, L.: Non-equilibrium statistical mechanics of anharmonic chains coupled to two heat baths at different temperatures. Commun. Math. Phys. 201, 657–697 (1999)
5. Eckmann, J.-P., Zabey, E.: Strange heat flux in (an)harmonic networks. J. Stat. Phys. 114, 515–523 (2004)
6. Hairer, M.: A probabilistic argument for the controllability of conservative systems. arxiv:math-ph/0506064
7. Hairer, M.: How hot can a heat bath get? Commun. Math. Phys. 292, 131–177 (2009)
8. Hörmander, L.: The Analysis of Linear Partial Differential Operators I–IV. New York: Springer, 1985
9. Jurdjevic, V.: Geometric control theory. Cambridge; New York: Cambridge University Press, 1997
10. Rey-Bellet, L.: Ergodic properties of Markov processes. Open Quantum Syst. II 139 (2006)
11. Rey-Bellet, L., Thomas, L.E.: Asymptotic behavior of thermal nonequilibrium steady states for a driven chain of anharmonic oscillators. Commun. Math. Phys. 215, 1–24 (2000)
12. Villani, C.: Hypocoercivity. Mem. Am. Math. Soc. 202, iv+141 (2009)