

# Optimal Control Problems for Elliptic Hemivariational Inequalities

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We consider a bounded domain  $\Omega$  in  $\mathbb{R}^d$  whose regular boundary  $\Gamma$  consist of the union of three disjoint portions  $\Gamma_i$ ,  $i = 1, 2, 3$  with  $meas(\Gamma_i) > 0$ . We formulate the following nonlinear elliptic problem with mixed boundary conditions [3]:

$$-\Delta u = g \text{ in } \Omega, \quad u|_{\Gamma_1} = 0, \quad -\frac{\partial u}{\partial n}|_{\Gamma_2} = q, \quad -\frac{\partial u}{\partial n}|_{\Gamma_3} \in \alpha \partial j(u), \quad (1)$$

where  $\alpha$  is a positive constant,  $g \in L^2(\Omega)$ ,  $q \in L^2(\Gamma_2)$  and the function  $j: \Gamma_3 \times \mathbb{R} \rightarrow \mathbb{R}$ , called a superpotential (nonconvex potential), is such that  $j(x, \cdot)$  is locally Lipschitz for a.e.  $x \in \Gamma_3$  and not necessary differentiable. Such multivalued condition on  $\Gamma_3$  is denoted for a nonmonotone relation expressed by the generalized gradient of Clarke [2]. The weak formulation of (1) is given by the elliptic hemivariational inequality [3, 5]:

$$\text{find } u \in V_0 \text{ such that } a(u, v) + \alpha \int_{\Gamma_3} j^0(u; v) d\Gamma \geq L(v), \quad \forall v \in V_0, \quad (2)$$

where  $j^0$  represent the generalized (Clarke) directional derivative,  $a(u, v) = \int_{\Omega} \nabla u \nabla v dx$ ,  $L(v) = \int_{\Omega} gv dx - \int_{\Gamma_2} qv d\gamma$  and  $V_0 = \{v \in H^1(\Omega) : v = 0 \text{ on } \Gamma_1\}$ .

We formulate for each  $\alpha > 0$ , different optimal control problems ( $C_\alpha$ ), on the internal energy  $g$  and the heat flux  $q$ , for quadratic cost functional and we prove existence results for the optimal solutions (see [1, 4]). We also consider a problem as (1), with a Dirichlet condition on  $\Gamma_3$  and we formulate similar optimal control problems ( $C$ ), on control variables  $g$  and  $q$ . We obtain, convergence results for optimal controls and system states ( $C_\alpha$ ) to the corresponding optimal control and system state ( $C$ ), when the parameter  $\alpha$  goes to infinity.

## Bibliography

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