Asymptotic behaviour of a simple cellular automaton: Use of scale invariance.

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- $\blacktriangleright$   $\mathcal{A}$  a finite alphabet ;
- $\mathcal{A}^{\mathbb{Z}}$  the set of **configurations**.

A cellular automaton (CA) is an action  $F : \mathcal{A}^{\mathbb{Z}} \to \mathcal{A}^{\mathbb{Z}}$  defined by a local rule  $f : \mathcal{A}^{[-r,r]} \to \mathcal{A}$  (for some r > 0).

Example with  $\mathcal{A} = \{\blacksquare, \Box\}$  and r = 1 :



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Example with  $\mathcal{A} = \{\blacksquare, \Box\}$  and r = 1:



Define the **shift** action as  $\sigma(a)_i = a_{i-1}$ .

### Initial measure

We are considering the case where the initial configuration is chosen at random.

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- $\mathcal{M}_{\sigma}(\mathcal{A}^{\mathbb{Z}})$ : set of  $\sigma$ -invariant probability measures;
- F extends to an action  $\mathcal{M}_{\sigma}(\mathcal{A}^{\mathbb{Z}}) \to \mathcal{M}_{\sigma}(\mathcal{A}^{\mathbb{Z}})$ ;
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Examples of initial measures:

- Bernoulli measures where each cell is drawn independently;
- Markov measures, which have finite memory;
- Hidden Markov (image of a Markov measure by a factor).

## Limit measures, $\mu$ -limit set

Asymptotic behaviour can be described by the persistent words, whose probability to appear does not tend to 0 as  $t \to \infty$ .

#### $\mu$ -limit set

The  $\mu$ -limit set  $\Lambda_{\mu}(F)$  is the set of configurations containing only persistent words.

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Alternatively, it can be described as the **support of the adherence** values of the sequence  $(F^n \mu)$  in the appropriate topology:

$$\mathcal{A}^{\mathbb{Z}}$$
:  $\mathcal{M}_{\sigma}(\mathcal{A}^{\mathbb{Z}})$ :

$$\begin{array}{ll} \text{Cantor distance} & \text{Lévy-Prohorov distance} \\ d_c(u,v) = |\mathcal{A}|^{-\min\{|n|; u_n \neq v_n\}} & d(\mu,\nu) = \sum_{u \in \mathcal{A}^*} \frac{\mu([u]_0) - \nu([u]_0)}{\mathcal{A}^{|u|}} \\ \text{Product topology} & \text{Weak-* convergence topology} \end{array}$$

# Self-organization: qualitative approach



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### Theorem [H., Sablik, 2011]

Let F be a CA,  $\mu$  a  $\sigma$ -ergodic measure. Define a "set of particles" evolving at constant "speed" and such that any particle interaction is "destructive".

Then particles appearing in  $\Lambda_{\mu}(F)$  all have the same speed.



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#### Gliders automaton

Let  $\mathcal{A} = \{+, 0, -\}$  and  $v_- < v_+$ . The  $(v_-, v_+)$ -gliders automaton is the CA with two particles: + evolving at speed  $v_+$ ; - evolving at speed  $v_-$ .



Figure:  $v_{-} = -1, v_{+} = 1$ 

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For any ergodic measure  $\mu$  with  $\mu([+]) = \mu([-])$ ,  $\Lambda_{\mu}$  contains no particle.

# Scope of our results

We will consider two families of initial measures :

- Ber the Bernoulli measures satisfying  $p_+ = p_- \neq 0$  (simple case);
- $\blacktriangleright$   $\mathcal{H}\mathcal{M}$  the hidden transitive, aperiodic Markov measures satisfying:

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$$\mu([+]) = \mu([-]);$$

•  $\sum_{k\geq 0} \mathbb{E}(\pi_0 \mu \cdot \pi_k \mu) > 0$  (asymptotic variance).

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Then we have  $\Phi : \mathcal{B}er \to \mathcal{HM}$ .

### Entry times

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Let  $v_- < v_+ \in \mathbb{Z}$  and  $a \in \mathcal{A}^{\mathbb{Z}}$ . If  $v_- \neq 0$ , we define:

$${\mathcal T}^-_n(a) = \min\{k \in {\mathbb N} \mid F^{k+n}(a)_{[0,|v_-|-1]} \text{ contains a particle } -1\}$$

respectively  $T_n^+(a)$ . This is the **entry time** of *a* into the set  $\{b \in \mathcal{A}^{\mathbb{Z}} \mid b_{[0,|\nu_-|-1]} \text{ contains a particle } -1\}$  after time *n* at position 0.



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# State of the art

#### Theorem (Denunzio, Formenti, Kurka, 2011)

Consider the (-1, 0)-gliders automaton with an initial Bernoulli measure of parameters  $p_+ = p_- = 1/2$ . Then:

$$\mathbb{P}\left(\frac{T_n^-(\mathsf{a})}{n} \le x\right) \xrightarrow[n \to \infty]{} \frac{2}{\pi} \arctan \sqrt{2x}.$$

Purely combinatorial approach.



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#### Conjecture (op.cit.)

If instead we have  $\mu \in \mathcal{B}\mathit{er}$ ,

$$\mathbb{P}\left(\frac{T_n^-(a)}{n} \le x\right) \xrightarrow[n \to \infty]{} \frac{2}{\pi} \arctan \sqrt{2px}.$$

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## Entry times

#### Theorem 1

- ▶  $(v_-, v_+)$ -gliders automaton with  $v_- \in \mathbb{Z}^-, v_+ \in \mathbb{Z}^+$ .
- $\blacktriangleright$  Initial measure in  $\mathcal{HM}$

Then for almost all initial configuration a,

$$\mathbb{P}\left(\frac{T_n^-(a)}{n} \le x\right) \xrightarrow[n \to \infty]{} \frac{2}{\pi} \arctan\left(\sqrt{\frac{-\nu_- x}{\nu_+ - \nu_- + \nu_+ x}}\right)$$

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and symmetrically for  $T_n^+$ .

#### Remarks

- ▶ Independent of  $\mu([+]), \mu([-]).$
- > This **disproves** the conjecture.

For  $a \in \mathcal{A}^{\mathbb{Z}}$ , we define the process  $M_a$  that:

- ▶ goes up when it meets a +;
- ▶ goes down when it meets a -.



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 $F_n(a)_0 = + \Leftrightarrow M_a$  on [-n, n] admits a **minimum** in -n. and symmetrically for -.





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Using scale invariance, we approximate the process by a  $\ensuremath{\textbf{Brownian}}$   $\ensuremath{\textbf{motion}}.$ 

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# Density of particles

Densities

For a configuration  $a \in \mathcal{A}^{\mathbb{Z}}$ , the **density of particles** - (resp. +) is:

$$d_{-}(a) = \limsup_{n \to \infty} \frac{\#\{i \in [-n, n] \mid a_i = -\}}{2n+1}$$

#### Theorem 2

For an initial measure  $\mu$ , we have:

• If  $\mu \in \mathcal{B}er$ :

For almost all 
$$a, d_-({{\mathsf F}}^n(a)) = \Theta\left(n^{-rac{1}{2}}
ight)$$

• If  $\mu \in \mathcal{HM}$ :

For almost all 
$$a, orall arepsilon > 0, d_-({F}^n(a)) = O\left(n^{-rac{1}{4}+arepsilon}
ight)$$

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and similarly for  $d_+$ .

# Rate of convergence

#### Theorem 3

Consider any  $(v_-, v_+)$ -gliders automaton with  $v_- < v_+$ .

•  $\mu \in \mathcal{HM}$  the initial measure,

 $\blacktriangleright$   $\lambda$  the limit measure (weighing only the particleless configuration),

► *d* be the Lévy-Prohorov distance defined earlier.

Then:

$$\forall \varepsilon > 0, \ d(F^n \mu, \lambda) = O\left(n^{-\frac{1}{8}+\varepsilon}\right)$$

If furthermore  $\mu \in \mathcal{B}er$ , we have:

$$d(F^n\mu,\lambda)=\Omega\left(n^{-\frac{1}{2}}\right)$$

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### Perspectives

- ▶ With the same approach, better understanding of the limit diagram.
- Extending this kind of results to more particles and different interactions, and eventually to whole classes of automata (e.g. captive automata)

