

# Backstepping boundary stabilization of cross-diffusion systems in a one-dimensional moving domain

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Cross-diffusion systems naturally arise in diffusion models of multi-species mixtures [3] and in particular in materials science to model atomic diffusion within solids. Indeed, hydrodynamic limits of some stochastic lattice hopping models [4] read as cross-diffusion systems of the form :

$$\partial_t u - \operatorname{div}_x (A(u) \nabla_x u) = 0, \quad (1)$$

where  $u := (u_1, \dots, u_n)$  models the local volumic fractions ( $\sum_j u_j \leq 1$ ,  $u_i \geq 0 \forall i$ ) of the different species and  $A : \mathbb{R}^n \rightarrow \mathbb{R}^{n \times n}$  is the diffusion matrix. In [1] the authors considered a cross-diffusion system defined in a one-dimensional moving boundary domain in order to model a Physical Vapor Deposition process (PVD) used for the fabrication of thin film layers in the photovoltaic industry. The process can be described as follows : a wafer is introduced in a hot chamber where chemical elements are injected under gaseous form. As the latter deposit on the substrate, a heterogeneous solid layer grows upon it. Because of the high temperature conditions, diffusion occurs in the bulk until the wafer is taken out and the system is frozen.

Let  $\phi(t) = (\phi_1(t) \geq 0, \dots, \phi_n(t) \geq 0)$  represent the fluxes of the different species absorbed at the surface of the film layer. Then the thickness  $e(t)$  of the film evolves according to :

$$e(t) = e_0 + \int_0^t \sum_{i=1}^n \phi_i(s) ds, \quad (2)$$

and the absorption condition on the boundary reads :

$$(A(u) \partial_x u)(t, e(t)) + e'(t) u(t, e(t)) = \phi(t). \quad (3)$$

This work is concerned with the stabilization of (1)-(2)-(3) around uniform equilibrium states using the control variables  $(\phi_i)_{1 \leq i \leq n}$  in (3). Under appropriate assumptions on  $A$  related to the *entropic structure* [3], we show rapid and even finite-time stabilization in  $L^2$  of the *linearized* system. The feedback control is derived using the backstepping technique inspired from [2], which consists in transforming the original system, hard to stabilize, into a simpler target system, using an isomorphism. The difficulties come from the time-dependence of the system that complicates the stability analysis and from the boundary condition (3) that leads to an only weakly defined feedback control in the  $L^2$  setting.

Upcoming work will be concerned with the consequences in terms of *local* stabilization of the *nonlinear* system. This is joint work with Virginie Ehrlacher and Amaury Hayat at Ecole des Ponts.

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