

A Mathematical study of Two Species Amensalism Model With a Cover for the first Species by Homotopy Analysis Method

B. Sita Rambabu¹, K. L. Narayan² and Shahanz Bathul³

¹Department of Basic sciences & Humanities .AVN Institute of Engineering & Technology, Hyd

²Department of Basic sciences & Humanities.SLC Institute of Engineering & Technology, Hyd

³Department of Basic sciences & Humanities. JNT University, Kukatpally, Hyd

ABSTRACT

The present paper is devoted to an analytical investigation of a two species amensalism model with a partial cover for the first species to protect it from the second species. The series solution of the non-linear system was approximated by the Homotopy analysis method (HAM) and the solutions are supported by numerical examples.

Key Words: Amensalism, zero order deformation, embedding parameter, linear operator, Non linear operator and HAM.

INTRODUCTION

Symbioses are a broad class of interactions among organisms --amensalism involves one organism affecting another negatively without any positive or negative benefit for itself.

A. V. N. Acharyulu and Patabhi Ramacharyulu [1,2,3,4] studied the stability of enemy amensal species pair with limited resources and B. Shiva Prakash and T. Karunanithi studied the interaction between schizosaccharomyces pombe and saccharomyces cerevisiae to predict stable operating conditions in a chemostat [5].

About HAM: In 1992 Liao employed the basic idea of homotopy in topology to propose a powerful analytical method for nonlinear problems namely Homotopy Analysis Method [6,7,8,9,10]. Later on M. Ayub, A. Rasheed, T. Hayat, Fadi & Awawdeh [11,12,13] successfully applied this technique to solve different types of non-linear problems. The HAM itself provides us with a convenient way to control adjust the convergence region and rate of approximation series. In this paper we propose HAM method to investigate the series solutions of a two species amensalism model with a cover for the first species to protect it from the attacks of the second species.

Examples: Avian botulism and "red tides" (caused by dino flagellates) are often extremely toxic for birds, marine mammals, humans; etc. Amensalism may lead to the pre-emptive colonization of a habitat. Once an organism establishes itself within a habitat it may prevent other populations from surviving in that habitat. The production of lactic acid or similar low-molecular-weight fatty acids is inhibitory to many bacterial populations. Populations able to produce and tolerate high concentrations of lactic acids, for example, are able to modify the habitat so as to preclude the growth of other bacterial populations. E.coli is unable to grow in the rumen, probably because of the presence of volatile fatty acids produced there by anaerobic heterotrophic microbial populations. Fatty acids

produced by microorganisms on skin surfaces are believed to prevent the colonization of these habitats by other microorganisms. Populations of yeasts on skin surfaces are maintained in low numbers by microbial populations producing fatty acids. Acids produced by microbial populations in the vaginal tract are probably responsible for preventing infection by pathogens such as *Candida albicans*.

In the present investigation a two species amensalism model with limited resources for both the species and a partial cover for the first species to protect it from the attacks of the second species was taken up for analytic study. The model is represented by coupled non-linear ordinary differential equations. The series solution of the non-linear system is approximated by Homotopy Analysis Method supported by numerical examples.

The governing equations of the system are as follows

$$\begin{aligned} \frac{dx}{dt} &= a_1x(t) - \alpha_{11}x^2(t) - \alpha_{12}(1-k)x(t)y(t) \\ \frac{dy}{dt} &= a_2y(t) - \alpha_{22}y^2(t) \end{aligned} \tag{1.1}$$

With the notation

$x(t)$, $y(t)$ are respectively the populations of species1 and species2, and k is a cover provided for the species1 $0 < k < 1$

2. Basic ideas of HAM:

In this paper, we apply the homotopy analysis method to the discussed problem. To show the basic idea, let us consider the following differential equation

$$N(u,t) = 0, \tag{2.1}$$

Where N is a nonlinear operator, t denote independent variable, $u(t)$ is an unknown function, respectively. For simplicity, we ignore all boundary or initial conditions, which can be treated in the similar way. By means of generalizing the traditional homotopy method, Liao constructs the so-called zero-order deformation equation

$$(1-p)L[\phi(t;p) - u_0(t)] = p\bar{h}H(t)N[\phi(t;p)], \tag{2.2}$$

Where $p \in [0,1]$ is the embedding parameter, \bar{h} is a nonzero auxiliary, parameter H is an auxiliary, parameter H is an auxiliary function L is an auxiliary linear operator, $u_0(t)$ is an initial guess of $u(t)$, $\phi(t;p)$ is a unknown function, respectively. It is important that one has great freedom to choose auxiliary things in HAM. Obviously,

When $p=0$ and $p=1$, it holds $\phi(t,0) = u_0(t)$, $\phi(t,1) = u(t)$ (2.3)

Respectively. Thus as p increases from 0 to 1, the solution $\phi(t;p)$ varies from the initial guesses $u_0(t)$ to the solution $u(t)$. Expanding $\phi(t;p)$ in Taylor series with respect to p , one has

$$\phi(t;p) = u_0(t) + \sum_{m=1}^{+\infty} u_m(t)p^m \tag{2.4}$$

Where

$$u_m(t) = \frac{1}{m!} \left. \frac{\partial^m \phi(t;p)}{\partial p^m} \right|_{p=0} \tag{2.5}$$

If the initial guess (2.3), the auxiliary linear parameter L , the non-zero auxiliary parameter h , and the auxiliary function H , are properly chosen, so that the power series (2.4) converges at $p=1$.

Then we have under these assumptions the solution series

$$u(t) = u_0(t) + \sum_{m=1}^{+\infty} u_m(t) \tag{2.6}$$

Which must be one of solution s of original non linear equation, as proved by Liao [15].As $\bar{h} = -1$ and $H(t)=1$,Eq (2.2) becomes

$$(1 - p)L[\phi(t; p) - u_0(t)] + pN[\phi(t; p)] = 0, \tag{2.7}$$

which is used mostly in the homotopy perturbation method, whereas the solution obtained directly, without using Taylor series which is explained by H. Jafari, M. Zabihi and M. Saidy [14] and J. H. He [15,16] and S. J. Liao [17] compare the HAM and HPM. According to the definition, the governing equation can be deduced from the zero-order deformation equation (2.7) . Define the vector

$$\vec{u}_k = \{u_0, u_1, \dots, u_k\}$$

Differentiating Eq. (2.7) ,m times with respect to embedding parameter p and then setting p=0 and finally dividing them by m! , we have the so-called mth-order deformation equation

$$L[u_m(t) - \chi_m u_{m-1}(t)] = \bar{h}H(t)R_m(\vec{u}_{m-1}), \tag{2.8}$$

Where

$$R_m(\vec{u}_{m-1}) = \frac{1}{(m-1)!} \left. \frac{\partial^{m-1} N[\phi(t; p)]}{\partial p^{m-1}} \right|_{p=0},$$

and

$$\chi_m = \begin{cases} 0, & m \leq 1, \\ 1, & m > 1. \end{cases} \tag{2.9}$$

3. Application:

Consider the nonlinear differential equation(1.1) with initial conditions .we assume the solution of the system(1.1) ,x(t),y(t) can be expressed by following set of base functions in the form

$$x(t) = \sum_{m=1}^{+\infty} a_m t^m, \quad y(t) = \sum_{m=1}^{+\infty} b_m t^m \tag{3.1}$$

Where a_m, b_m are coefficients to be determined. This provides us the so called rule of solution expression i.e., the solution of (1.1) must be expressed in the same from as (3.1) and the other expressions must be avoided. According to (1.1) and (3.1) we chose the linear operator.

To solve the system of Eqs.(1.1),Homotopy analysis method is employed. We consider the following initial approximations

$$x_0(t) = x(t=0) = x_0 \quad y_0(t) = y(t=0) = y_0 \tag{3.2}$$

The linear and non-linear operators are denoted as follows.

$$L_1[x(t; p)] = \frac{dx(t; p)}{dt}, \quad L_2[y(t; p)] = \frac{dy(t; p)}{dt}, \tag{3.3}$$

$$N_1[x(t, p)] = \frac{dx(t; p)}{dt} - a_1 x(t; p) + \alpha_{11} x^2(t; p) + \alpha_{12} (1 - k) x(t; p) y(t; p) \tag{3.4}$$

$$N_2[y(t, p)] = \frac{dy(t; p)}{dt} - a_2 y(t; p) + \alpha_{22} y^2(t; p) \tag{3.5}$$

Using above definition the zero order deformation equation can be constructed as

$$(1 - p)L_1[x(t; p) - x_0(t)] = ph_1 N_1[x, y], (1 - p)L_2[y(t; p) - y_0(t)] = ph_2 N_2[x, y] \tag{3.6}$$

When p=0 and p=1, from the zero-deformation equations one has,

$$x(t; 0) = x_0(t) \quad x(t; 1) = x(t), \quad y(t; 0) = y_0(t) \quad y(t; 1) = y(t) \tag{3.7}$$

And expanding x(t;p) and y(t;p) in Taylors series, with respect to embedding parameter p, one obtains

$$x(t; p) = x_0(t) + \sum_{m=1}^{+\infty} x_m(t) p^m, \quad y(t; p) = y_0(t) + \sum_{m=1}^{+\infty} y_m(t) p^m \tag{3.8}$$

Where $x_m(t) = \frac{1}{m!} \left. \frac{d^m x(t; p)}{dp^m} \right|_{p=0}, \quad y_m(t) = \frac{1}{m!} \left. \frac{d^m y(t; p)}{dp^m} \right|_{p=0}$ (3.9)

$$p = 1 \{ x_m(t) = x_0(t) + \sum_{m=1}^{+\infty} x_m(t), \quad y_m(t) = y_0(t) + \sum_{m=1}^{+\infty} y_m(t) \} \tag{3.10}$$

Define the vector

$$\vec{x}_m = [x_0(t), x_1(t), \dots, x_m(t)], \quad \vec{y}_m = [y_0(t), y_1(t), \dots, y_m(t)] \tag{3.11}$$

And apply the procedure stated before. The following mth-order deformation Eq will be achieved.

$$\begin{aligned} L_1[x_m(t) - \mathcal{X}_m x_{m-1}(t)] &= \bar{h}_1 H_1(t) R_{1m}(\vec{x}_{m-1}, \vec{y}_{m-1}), \\ L_2[y_m(t) - \mathcal{Y}_m y_{m-1}(t)] &= \bar{h}_2 H_2(t) R_{2m}(\vec{x}_{m-1}, \vec{y}_{m-1}), \end{aligned} \tag{3.12}$$

Let us consider $H_1(t) = H_2(t) = 1$ and the initial conditions

$$x_0(t) = x(t=0) = x_0 \quad y_0(t) = y(t=0) = y_0 \text{ in above equations}$$

$$R_{1m}(x_{m-1}, y_{m-1}) = \frac{1}{(m-1)!} \frac{d^{m-1}}{dp^{m-1}} N[x(t, p)] = \frac{d}{dt} x_{m-1}(t) - a_1 x_{m-1} + \alpha_{11} \sum_{n=1}^m x_n(t) x_{m-n-1}(t) + \alpha_{12} (1-k) \sum_{n=0}^{m-1} x_n(t) y_{m-n-1}(t)$$

$$R_{2m}(x_{m-1}, y_{m-1}) = \frac{1}{(m-1)!} \frac{d^{m-1}}{dp^{m-1}} N[y(t, p)] = \frac{d}{dt} y_{m-1}(t) - a_2 y_{m-1} + \alpha_{22} \sum_{n=1}^m y_n(t) y_{m-n-1}(t) \tag{3.13}$$

The following will be obtained successively

$$L_1(x_1(t) - \chi_1 x_0(t)) = h_1 \left[\frac{d}{dt} x_0(t) - a_1 x_0(t) + \alpha_{11} x_0^2(t) + \alpha_{12} (1-k) x_0(t) y_0(t) \right]$$

$$\chi_m(t) = 0, m \leq 0 \text{ and } 1, m > 0$$

$$L_1(x_1(t)) = h_1 \left[-a_1 x_0(t) + \alpha_{11} x_0^2(t) + \alpha_{12} (1-k) x_0(t) y_0(t) \right]$$

$$x_1(t) = h_1 \left[-a_1 x_0 + \alpha_{11} x_0^2 + \alpha_{12} (1-k) x_0 y_0 \right] t$$

$$L_1(y_1(t) - \chi_1 y_0(t)) = h_2 \left[\frac{d}{dt} y_0(t) - a_2 y_0(t) + \alpha_{22} y_0^2(t) \right]$$

$$L_1(y_1(t)) = h_2 \left[-a_2 y_0(t) + \alpha_{22} y_0^2(t) \right]$$

$$y_1(t) = h_2 \left[-a_2 y_0 + \alpha_{22} y_0^2 \right] t$$

$$L_1(x_2(t) - \chi_2 x_1(t)) = h_1 \left[\frac{d}{dt} x_1(t) - a_1 x_1(t) + \alpha_{11} \sum_{n=0}^1 x_n(t) x_{1-n}(t) + \alpha_{12} (1-k) \sum_{n=0}^1 x_n(t) y_{1-n}(t) \right]$$

$$x_2(t) = (h_1 + h_1^2) M_1 t + \frac{t^2}{2} \left[-a_1 h_1^2 M_1 + 2\alpha_{11} x_0 h_1 M_1 + \alpha_{12} (1-k) y_0 M_1 + h_2 a_2 \alpha_{12} (1-k) x_0 \right]$$

where $M_1 = -a_1 x_0 + \alpha_{11} x_0^2 + \alpha_{12} (1-k) x_0 y_0$

$$L_1(y_2(t) - \chi_2 y_1(t)) = h_2 \left[\frac{d}{dt} y_1(t) - a_2 y_1(t) + \alpha_{22} \sum_{n=0}^1 y_n(t) y_{1-n}(t) \right]$$

$$y_2(t) = (h_2 + h_2^2) \left[-a_2 y_0 + \alpha_{22} y_0^2 \right] t + \frac{h_2^2 y_0}{2} \left[\left(a_2^2 - 3a_2 \alpha_{22} y_0 + 2\alpha_{22}^2 y_0^2 \right) \right] t^2$$

$$L_1(x_3(t) - \chi_3 x_2(t)) = h_1 \left[\frac{d}{dt} x_2(t) - a_1 x_2(t) + \alpha_{11} \sum_{n=0}^2 x_n(t) x_{2-n}(t) + \alpha_{12} (1-k) \sum_{n=0}^2 x_n(t) y_{2-n}(t) \right]$$

$$x_3(t) = (1+h_1)(h_1 + h_1^2) M_1 t + \left[(1+h_1) M_2 + h_1 \alpha_{12} y_0 (h_1 + h_1^2) M_1 + \alpha_{12} h_1 x_0 (h_2 + h_2^2) (-a_2 y_0 + \alpha_{22} y_0^2) \right] \frac{t^2}{2}$$

$$+ \left[-2a_1 h_1 M_2 + 2h_1 \alpha_{11} M_2 x_0 + \alpha_{11} h_1^3 M_1^2 + 2h_1 \alpha_{12} h_2^2 x_0 y_0^2 (a_2^2 - 3a_2 \alpha_{22} y_0 + 2\alpha_{22}^2 y_0^2) + h_1^2 h_2 \alpha_{12} M_1 (-a_2 y_0 + \alpha_{22} y_0^2) + 2h_1 \alpha_{12} M_2 y_0 \right] \frac{t^3}{3}$$

$$M_2 = \left[-a_1 h_1^2 (1-k) M_1 + 2h_1 \alpha_{11} x_0 M_1 + \alpha_{12} (1-k) y_0 M_1 + h_2 \alpha_{12} \alpha_{22} x_0 (1-k) y_0^2 - h_2 \alpha_{12} a_2 x_0 (1-k) \right]$$

$$L_1(y_3(t) - \chi_3 y_2(t)) = h_2 \left[\frac{d}{dt} y_2(t) - a_2 y_2(t) + \alpha_{22} \sum_{n=0}^2 y_n(t) y_{2-n}(t) \right]$$

$$y_3(t) = (1+h_2) k_3 t + \left[(1+h_2) k_4 - a_2 h_2 k_3 + 2h_2 k_3 \alpha_{22} y_0 \right] \frac{t^2}{2} + \left[\left(-\frac{1}{2} a_2 h_2 k_4 + h_2 \alpha_{22} k_4 y_0 + \frac{\alpha_{22} h_2^3 k_3^2}{(h_2 + h_2^2)^2} \right) \right] \frac{t^3}{3}$$

Where

$$k_1 = [-a_1 x_0 + \alpha_{11} x_0^2 + \alpha_{12} x_0 y_0]$$

$$k_2 = \frac{h_1 x_0}{2} \left[h_1 (-a_1 + \alpha_{11} x_0 + \alpha_{12} y_0) (-a_1 + 2\alpha_{11} x_0 + \alpha_{12} y_0) + h_2 \alpha_{12} (-a_2 y_0 + \alpha_{22} y_0^2) \right]$$

$$k_3 = (h_2 + h_2^2) [-a_2 y_0 + \alpha_{22} y_0^2]$$

$$k_4 = \frac{h_2^2 y_0}{2} \left[(a_2^2 - 3a_2 \alpha_{22} y_0 + 2\alpha_{22}^2 y_0^2) \right]$$

The three terms approximation to the solution will be considered as

$$x(t) \approx x_0 + x_1(t) + x_2(t) + x_3(t)$$

$$y(t) \approx y_0 + y_1(t) + y_2(t) + y_3(t)$$

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