

215. Integration of Equations of Imschenetsky Type by Integrable Systems

By Michihiko MATSUDA

Department of Mathematics, Osaka University

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1. Introduction. Generalizing the method of integration due to Monge, the author gave a method of integration by integrable systems in [1] and [2]. Here we shall prove the following

Theorem. *Transform an equation of Imschenetsky type by one of the associated Imschenetsky transformations. Then the transformed equation is solved by integrable systems of order $n-1$, if and only if the original equation is solved by integrable systems of order n .*

This is a generalization of results in [1], [2] obtained for the Laplace transformation associated with a linear hyperbolic equation, and for the Imschenetsky transformation associated with an equation of Laplace type. In the second case the theorem was proved only for $n=1, 2$. In both the cases the author obtained the invariants of the equation whose vanishing is a necessary and sufficient condition in order that the equation may be solved by integrable systems of order n , and proved that the invariants for the original equation to be solved by integrable systems of order n are transformed to those for the transformed equation to be solved by integrable systems of order $n-1$. Here we shall prove the theorem directly, without obtaining the invariants of the equations.

2. Integrable systems of order n . Let us try to solve the Cauchy problem of an equation of type

$$(1) \quad s + f(x, y, z, p, q) = 0,$$

integrating ordinary differential equations, in the space of $(x, y, z, p, q_1, \dots, q_n)$. Here, $p = \partial z / \partial x$, $q = \partial z / \partial y$, $s = \partial^2 z / \partial x \partial y$, and $q_i = \partial^i z / \partial y^i$ ($q_1 = q$). The Cauchy problem in this space involving the derivatives of higher order is to find a two-dimensional submanifold which satisfies

$$(2) \quad \begin{aligned} dz - p dx - q dy &= dq_1 + f_0 dx - q_2 dy = dq_2 + f_1 dx - q_3 dy \\ &= \dots = dq_{n-1} + f_{n-2} dx - q_n dy = 0, \end{aligned}$$

and contains a given initial curve satisfying (2). Here, f_i is a function of $(x, y, z, p, q_1, \dots, q_{i+1})$ defined inductively by

$$f_i = \left(G_i - f \frac{\partial}{\partial p} \right) f_{i-1} \quad (i \geq 1), \quad f_0 = f$$

with