



HAL
open science

An example of non-uniqueness for Radon transforms with continuous positive rotation invariant weights

Fedor Goncharov, Roman Novikov

► **To cite this version:**

Fedor Goncharov, Roman Novikov. An example of non-uniqueness for Radon transforms with continuous positive rotation invariant weights. 2017. hal-01593781v1

HAL Id: hal-01593781

<https://hal.science/hal-01593781v1>

Preprint submitted on 26 Sep 2017 (v1), last revised 14 Nov 2017 (v2)

HAL is a multi-disciplinary open access archive for the deposit and dissemination of scientific research documents, whether they are published or not. The documents may come from teaching and research institutions in France or abroad, or from public or private research centers.

L'archive ouverte pluridisciplinaire **HAL**, est destinée au dépôt et à la diffusion de documents scientifiques de niveau recherche, publiés ou non, émanant des établissements d'enseignement et de recherche français ou étrangers, des laboratoires publics ou privés.

An example of non-uniqueness for Radon transform with continuous positive rotation invariant weight

F.O. Goncharov* R. G. Novikov*†

September 26, 2017

Abstract

We consider weighted Radon transforms R_W along hyperplanes in \mathbb{R}^3 with strictly positive weights W . We construct an example of such a transform with non-trivial kernel $\text{Ker}R_W$ in the space of infinitely smooth compactly supported functions and with continuous weight. Moreover, in this example the weight W is rotation invariant. In particular, by this result we continue studies of Quinto (1983), Markoe, Quinto (1985), Boman (1993) and Goncharov, Novikov (2017). We also extend our example to the case of weighted Radon transforms along two-dimensional planes in \mathbb{R}^d , $d \geq 3$.

1 Introduction

We consider weighted Radon transforms R_W in \mathbb{R}^d defined by

$$R_W f(s, \theta) = \int_{x\theta=s} W(x, \theta) f(x) dx, \quad (1.1)$$
$$s \in \mathbb{R}, \theta \in \mathbb{S}^{d-1}, x \in \mathbb{R}^d, d \geq 2,$$

where $W = W(x, \theta)$ is the weight, $f = f(x)$ is a test function on \mathbb{R}^d .

We assume that

$$W = \overline{W} \geq c > 0, W \in L^\infty(\mathbb{R}^d \times \mathbb{S}^{d-1}), \quad (1.2)$$

where \overline{W} denotes the complex conjugate of W , c is a constant.

The aforementioned transforms R_W arise in various domains of pure and applied mathematics; see, e.g., [Bey84], [Bey85], [BQ87], [Bom93], [Fi86], [FNatt01], [GN16], [Gon17], [GN17], [Kun92], [Nov14], [Qui83], [Qui83Err] and references therein.

In particular, studies on the transforms R_W under assumptions (1.2) were recently continued in [GN16], [Gon17], [GN17] for $d \geq 3$.

Note that the works [GN16], [Gon17] extend to the case of R_W , $d \geq 3$, the two-dimensional injectivity and reconstruction results of [Kun92], [Nov11], [Nov14], [GuiNov14].

On the other hand, under assumptions (1.2), the work [GN17] gives an example of R_W , $d \geq 3$, with non-trivial kernel in $C_0^\infty(\mathbb{R}^d)$ (infinitely smooth functions with compact support). This example was constructed in [GN17] proceeding from the example of non-uniqueness of [Bom93] for R_W in \mathbb{R}^2 and a recent result of [GN16].

In the two-dimensional example of non-uniqueness of [Bom93] the weight W satisfies (1.2), for $d = 2$, and is infinitely smooth everywhere. In the multidimensional example of non-uniqueness of [GN17] the weight satisfies (1.2), for $d \geq 3$, is infinitely smooth almost everywhere but is not yet continuous at some points.

In the present work we construct an example of R_W , for $d = 3$, with non-trivial kernel in $C_0^\infty(\mathbb{R}^3)$, where W satisfies (1.2) and is continuous everywhere. Moreover, in this example W is rotation invariant and $R_W f \equiv 0$ for some non-zero spherically symmetric $f \in C_0^\infty(\mathbb{R}^3)$.

The rotation invariance of the latter example is its principal advantage in comparison with the aforementioned examples of [Bom93] and [GN17].

By our rotation invariant example of non-uniqueness we also continue studies of [MQ85], where an example of non-uniqueness for R_W was constructed for $d = 2$. In the example of [MQ85] the weight W is bounded and positive but is not yet continuous and strictly positive. The continuity and strict positivity of W is the principal advantage of the example of the present work in comparison with the example of [MQ85].

*CMAP, Ecole Polytechnique, CNRS, Université Paris-Saclay, 91128, Palaiseau, France;
email: fedor.goncharov.ol@gmail.com

†IEPT RAS, 117997 Moscow, Russia;
email: roman.novikov@polytechnique.edu

Following [Qui83] we say that W is rotation invariant if and only if

$$W(x, \theta) = U(|x - (x\theta)\theta|, x\theta), \quad x \in \mathbb{R}^d, \theta \in \mathbb{S}^{d-1}, \quad (1.3)$$

for some positive and continuous U such that

$$U(r, s) = U(-r, s) = U(r, -s), \quad r \in \mathbb{R}, s \in \mathbb{R}. \quad (1.4)$$

On the other hand, we recall that weighted Radon transforms R_W in \mathbb{R}^d with smooth weights W satisfying properties (1.2), (1.3), (1.4) are injective for $f \in L_0^2(\mathbb{R}^d)$ (square integrable functions on \mathbb{R}^d with compact support); see [Qui83]. Here the smoothness of W can be specified, at least, as C^1 for $d = 2$ and $d = 3$. In view of the aforementioned counterexamples of [MQ85] and of the present work, some smoothness of W is crucial for these injectivity results.

In the present work we also extend our rotation invariant example of non-uniqueness for R_W in \mathbb{R}^3 to the case of weighted Radon transforms $R_W^{d,2}$ along two-dimensional planes in \mathbb{R}^d , $d > 3$; see Section 4. In this case $R_W^{d,2}f$ is defined on $\mathcal{P}^{d,2}$ (manifold of all oriented two-dimensional planes in \mathbb{R}^d) and is overdetermined already. That is

$$\dim \mathcal{P}^{d,2} = 3d - 6 > \dim \mathbb{R}^d = d \text{ for } d > 3. \quad (1.5)$$

Nevertheless, $R_W^{d,2}f \equiv 0$ on $\mathcal{P}^{d,2}$ in our result.

We expect that the results of the present work admit generalizations to the weighted Radon transforms $R_W^{d,n}$ along n -dimensional planes in \mathbb{R}^d for arbitrary d and n such that $1 \leq n < d$, $d \geq 2$. For $n = 1$ such results are already obtained in [GonNov17].

Note also that the construction of the present work was developed in a large extent in the process of adopting the Boman's construction of the aforementioned work [Bom93].

In Section 2 we give some preliminaries.

Our main results are formulated in detail in Sections 3, 4.

Proofs are given in Sections 5-8.

2 Some preliminaries

Notations for $d = 3$. Let

$$B = \{x \in \mathbb{R}^3 : |x| < 1\}, \overline{B} = \{x \in \mathbb{R}^3 : |x| \leq 1\}, \quad (2.1)$$

$$\mathcal{P} = \mathbb{R} \times \mathbb{S}^2, \quad (2.2)$$

$$\mathcal{P}_0(\delta) = \{(s, \theta) \in \mathcal{P} : |s| > \delta\}, \quad (2.3)$$

$$\mathcal{P}_1(\delta) = \mathcal{P} \setminus \mathcal{P}_0(\delta) = \{(s, \theta) \in \mathcal{P} : |s| \leq \delta\}, \delta > 0, \quad (2.4)$$

$$\mathcal{P}(\Lambda) = \{(s, \theta) \in \mathcal{P} : s \in \Lambda\}, \Lambda \subset \mathbb{R}, \quad (2.5)$$

$$\Omega(\Lambda) = \{(x, \theta) \in \mathbb{R}^3 \times \mathbb{S}^2 : x\theta \in \Lambda\}, \Lambda \subset \mathbb{R}, \quad (2.6)$$

$$\mathcal{J}_{s,\varepsilon} = \mathcal{J}_{|s|,\varepsilon} = (|s| - \varepsilon, |s| + \varepsilon) \cup (|s| - \varepsilon, |s| + \varepsilon) \subset \mathbb{R}, s \in \mathbb{R}, \varepsilon > 0. \quad (2.7)$$

Note that $\mathcal{P}_0(\delta), \mathcal{P}_1(\delta)$ of (2.3), (2.4) are particular cases of $\mathcal{P}(\Lambda)$ of formula (2.5).

In addition, we interpret \mathcal{P} as the set of all oriented planes in \mathbb{R}^3 . If $P = (s, \theta) \in \mathcal{P}$, then

$$P = P_{(s,\theta)} = \{x \in \mathbb{R}^3 : x\theta = s\} \text{ (modulo orientation)} \quad (2.8)$$

and θ gives the orientation of P (in the sense that ordered tuple (e_1, e_2, θ) is positively oriented in \mathbb{R}^3 with any orthonormal positively oriented basis e_1, e_2 on P).

The set $\mathcal{P}_0(\delta)$ in (2.3) is considered as the set of all oriented planes in \mathbb{R}^3 which are positioned at distance greater than δ from the origin.

The set $\mathcal{P}_1(\delta)$ in (2.4) is considered as the set of all oriented planes in \mathbb{R}^3 which are located at distance less or equal than δ .

Rotation invariancy for $d = 3$. Symmetries (1.3), (1.4) of W can be also written as

$$W(x, \theta) = \tilde{U}(|x|, x\theta), \quad x \in \mathbb{R}^3, \theta \in \mathbb{S}^2, \quad (2.9)$$

$$\tilde{U}(r, s) = \tilde{U}(r, -s), \quad \tilde{U}(r, s) = \tilde{U}(-r, s), \quad r \in \mathbb{R}, s \in \mathbb{R}, \quad (2.10)$$

where \tilde{U} is positive and continuous on $\mathbb{R} \times \mathbb{R}$. Using the formula $|x|^2 = |x\theta|^2 + |x - (x\theta)\theta|^2$, $\theta \in \mathbb{S}^2$, one can see that symmetries (1.3), (1.4) and symmetries (2.9), (2.10) of W are equivalent.

Additional notations. For a function f on \mathbb{R}^d we denote its restriction to a subset Σ by $f|_\Sigma$.

By C_0, C_0^∞ we denote continuous compactly supported and infinitely smooth compactly supported functions, respectively.

Partition of unity. We recall the following classical result (see Theorem 5.6 in [MCar92]):
Let \mathcal{M} be a C^∞ -manifold, which is Hausdorff and satisfies second countability axiom (i.e. has countable base). Let also $\{U_i\}_{i=1}^\infty$ be the open locally-finite cover of \mathcal{M} .

Then there exists a C^∞ -smooth locally-finite partition of unity $\{\psi_i\}_{i=1}^\infty$ on \mathcal{M} , such that

$$\text{supp } \psi_i \subset U_i. \quad (2.11)$$

In particular, any open interval $(a, b) \subset \mathbb{R}$ and $\mathcal{P} \simeq \mathbb{R} \times \mathbb{S}^2$ satisfy conditions of the aforementioned statement. It will be used in Subsection 3.4.

3 Main results for $d = 3$

Theorem 1. *There exist a non-zero spherically symmetric function $f \in C_0^\infty(\mathbb{R}^3)$ with support in \overline{B} , and W satisfying (1.2)-(1.4) such that*

$$R_W f \equiv 0, \quad (3.1)$$

where R_W is defined in (1.1).

The construction of f and W proving Theorem 1 is presented below in this section. This construction adopts considerations of [Bom93]. In particular, we construct f , first, and then W .

3.1 Construction of f

The function f is constructed as follows:

$$f = \sum_{k=1}^{\infty} \frac{f_k}{k!}, \quad (3.2)$$

$$f_k(x) = f_k(|x|) = \Phi(2^k(1 - |x|)) \cos(8^k |x|^2), x \in \mathbb{R}^3, k = 1, 2, \dots, \quad (3.3)$$

for arbitrary $\Phi \in C^\infty(\mathbb{R})$ such that

$$\text{supp } \Phi = [4/5, 6/5], \quad (3.4)$$

$$0 < \Phi(t) \leq 1 \text{ for } t \in (4/5, 6/5), \quad (3.5)$$

$$\Phi(t) = 1 \text{ for } t \in [9/10, 11/10]. \quad (3.6)$$

Properties (3.4), (3.5) imply that functions f_k in (3.3) have disjoint supports and series (3.2) converges for every fixed $x \in \mathbb{R}^3$.

Lemma 1. *Let f be defined by (3.2)-(3.6). Then f is spherically symmetric, $f \in C_0^\infty(\mathbb{R}^3)$ and $\text{supp } f \subseteq \overline{B}$. In addition, if $P \in \mathcal{P}$, $P \cap B \neq \emptyset$, then $f|_P \not\equiv 0$ and $f|_P$ has non-constant sign.*

Lemma 1 is proved in Section 5.

3.2 Construction of W

In our example W is of the following form:

$$\begin{aligned} W(x, \theta) &= \sum_{i=0}^N \xi_i(|x\theta|) W_i(x, \theta) \\ &= \xi_0(|x\theta|) W_0(x, \theta) + \sum_{i=1}^N \xi_i(|x\theta|) W_i(x, \theta), x \in \mathbb{R}^3, \theta \in \mathbb{S}^2, \end{aligned} \quad (3.7)$$

where

$$\{\xi_i(s), s \in \mathbb{R}\}_{i=0}^N \text{ is a } C^\infty\text{-smooth partition of unity on } \mathbb{R}, \quad (3.8)$$

$$\xi_i(s) = \xi_i(-s), s \in \mathbb{R}, i = \overline{0, N}, \quad (3.9)$$

$$\begin{aligned} W_i(x, \theta) \text{ are bounded continuous strictly positive and} \\ \text{rotation invariant (according to (1.3), (1.4)) on } \text{supp } \xi_i(|x\theta|), i = \overline{0, N}, \text{ respectively.} \end{aligned} \quad (3.10)$$

From (3.7)-(3.10) it follows that W of (3.7) satisfies the conditions (1.2)-(1.4).

The weight W_0 is constructed in Subsection 3.3 and has the following properties:

$$W_0 \text{ is bounded, continuous and rotation invariant on } \{(x, \theta) : |x\theta| > 1/2\}, \quad (3.11)$$

there exists $\delta_0 \in (1/2, 1)$ such that:

$$W_0(x, \theta) \geq 1/2 \text{ if } |x\theta| > \delta_0, \quad (3.12)$$

$$W_0(x, \theta) = 1 \text{ if } |x\theta| \geq 1,$$

$$R_{W_0} f(s, \theta) = 0 \text{ for } |s| > 1/2, \theta \in \mathbb{S}^2, \quad (3.13)$$

where R_{W_0} is defined according to (1.1) for $W = W_0$, f is given by (3.2), (3.3).

In addition,

$$\text{supp } \xi_0 \subset (-\infty, -\delta_0) \cup (\delta_0, +\infty), \quad (3.14)$$

$$\xi_0(s) = 1 \text{ for } |s| \geq 1, \quad (3.15)$$

where δ_0 is the number of (3.12).

In particular, from (3.8), (3.12), (3.14) it follows that

$$W_0(x, \theta)\xi_0(|x\theta|) > 0 \text{ if } \xi_0(|x\theta|) > 0. \quad (3.16)$$

Remark 1. The result of (3.11)-(3.13) can be considered as a counterexample to the Cormack-Helgason support theorem (see Theorem 3.1 in [FNatt01]) in the framework of the theory of weighted Radon transforms under assumptions (1.2) and even under assumptions (1.2)-(1.4).

In addition,

$$\xi_i(|x\theta|)W_i(x, \theta) \text{ are bounded, continuous and rotation invariant on } \mathbb{R}^3 \times \mathbb{S}^2, \quad (3.17)$$

$$W_i(x, \theta) \geq 1/2 \text{ if } \xi_i(|x\theta|) \neq 0, \quad (3.18)$$

$$R_{W_i}f(s, \theta) = 0 \text{ if } \xi_i(|s|) \neq 0, \quad (3.19)$$

$$i = \overline{1, N}, x \in \mathbb{R}^3, \theta \in \mathbb{S}^2, s \in \mathbb{R}. \quad (3.20)$$

Weights W_1, \dots, W_N of (3.7) and $\{\xi_i\}_{i=0}^N$ are constructed in Subsection 3.4.

Result of Theorem 1 follows from Lemma 1 and formulas (3.7)-(3.9), (3.11)-(3.13), (3.16)-(3.20).

We point out that the construction of W_0 of (3.7) is substantially different from the construction of W_1, \dots, W_N . In particular, the weight W_0 is defined on the planes $P \in \mathcal{P}$ which can be close to the boundary ∂B of B which results in restrictions on the smoothness of W_0 .

3.3 Construction of W_0

Let

$$\{\psi_k\}_{k=1}^\infty \text{ be a } C^\infty \text{ partition of unity on } (1/2, 1), \text{ such that } \text{supp } \psi_k \subset (1 - 2^{-k+1}, 1 - 2^{-k-1}), k \in \mathbb{N}. \quad (3.21)$$

Note that

$$1 - 2^{-(k-2)-1} < 1 - 2^{-k}(6/5), k \geq 3. \quad (3.22)$$

Therefore,

$$\forall s_0, t_0 \in \mathbb{R} : s_0 \in \text{supp } \psi_{k-2}, t_0 \in \text{supp } \Phi(2^k(1-t)) \Rightarrow s_0 < t_0, k \geq 3. \quad (3.23)$$

The weight W_0 is defined by the following formulas

$$W_0(x, \theta) = \begin{cases} 1 - G(x, \theta) \sum_{k=3}^\infty k! f_k(x) \frac{\psi_{k-2}(|x\theta|)}{H_k(x, \theta)}, & 1/2 < |x\theta| < 1, \\ 1, & |x\theta| \geq 1 \end{cases}, \quad (3.24)$$

$$G(x, \theta) = \int_{y\theta=x\theta} f(y) dy, H_k(x, \theta) = \int_{y\theta=x\theta} f_k^2(y) dy, \quad (3.25)$$

$$x \in \mathbb{R}^3, \theta \in \mathbb{S}^2,$$

where f_k are defined in (3.3).

Formula (3.24) implies that W_0 is defined on $\mathcal{P}_0(1/2) \subset \mathcal{P}$. Due to (3.3) and (3.23), in (3.25) we have that $H_k(x, \theta) \neq 0$ if $\psi_{k-2}(|x\theta|) \neq 0$.

Also, for any fixed $(x, \theta) \in \mathbb{R}^3 \times \mathbb{S}^2$, $1/2 < |x\theta| < 1$, the series in the right hand-side of (3.24) has only a finite number of non-zero terms (in fact, no more than two) and, hence, W_0 is well-defined.

By the spherical symmetry of f , functions G, H_k in (3.24) are of the type (2.9), (2.10). Therefore, W_0 is rotation invariant (in the sense (2.9), (2.10)).

Actually, formula (3.13) follows from (3.2)-(3.4), (3.24), (3.25) (see Subsection 5.2 for details).

Using the construction of W_0 and the assumption that $|x\theta| > 1/2$ (implying that $\text{sign}(x\theta)$ is locally constant) one can see that W_0 is C^∞ on its domain of definition, possibly, except points with $|x\theta| = 1$.

Lemma 2. Let W_0 be defined by (3.24), (3.25). Then the following estimate holds:

$$|1 - W_0(x, \theta)| \leq C_0 \rho(|x\theta|) \left(\log_2 \frac{1}{\rho(|x\theta|)} \right)^4, \quad (3.26)$$

$$W_0(x, \theta) \rightarrow 1 \text{ as } |x\theta| \rightarrow 1, \quad (3.27)$$

$$x \in \mathbb{R}^3, \theta \in \mathbb{S}^2, 1/2 < |x\theta| < 1.$$

where $\rho = \rho(s) = 1 - s$, $s \in (1/2, 1)$, C_0 is a positive constant depending on Φ .

Lemma 2 is proved in Section 6.

The result of Lemma 2 completes the proof of (3.12).

This completes the description of W_0 and δ_0 .

3.4 Construction of W_1, \dots, W_N and ξ_0, \dots, ξ_N

Lemma 3. *Let $f \in C_0(\mathbb{R}^3)$ be spherically symmetric, $P_{(s_0, \theta_0)} \in \mathcal{P}$, $f|_{P_{(s_0, \theta_0)}} \neq 0$ and $f|_{P_{(s_0, \theta_0)}}$ changes the sign. Then:*

(i) *there exist $\varepsilon > 0$ and weight $W_{f, s_0, \varepsilon}$ such that*

$$RW_{f, s_0, \varepsilon} f(s, \theta) = 0 \text{ for } s \in \mathcal{J}_{s_0, \varepsilon}, \theta \in \mathbb{S}^2, \quad (3.28)$$

where $\mathcal{J}_{s, \varepsilon}$ is defined in (2.7), $W_{f, s_0, \varepsilon}$ is defined on the open set $\Omega(\mathcal{J}_{s_0, \varepsilon})$, defined by (2.6);

(ii) *weight $W_{f, s_0, \varepsilon}$ is bounded, continuous, strictly positive and rotation invariant on $\Omega(\mathcal{J}_{s_0, \varepsilon})$.*

Lemma 3 is proved in Section 7.

Let f be the function of (3.2), (3.3). Then, using Lemmas 1, 3 one can see that

$$\begin{aligned} \forall \delta \in (0, 1) \text{ there exist } \{J_i = \mathcal{J}_{s_i, \varepsilon_i}, W_i = W_{f, s_i, \varepsilon_i}\}_{i=1}^N \\ \text{such that } J_i, i = \overline{1, N}, \text{ is an open cover of } [-\delta, \delta] \\ \text{and } W_i \text{ satisfy (i) and (ii) (of Lemma 3) on } \Omega(J_i). \end{aligned} \quad (3.29)$$

Actually, we consider (3.29) for the case of $\delta = \delta_0$ of (3.12).

Note that in this case $\{\mathcal{P}(J_i)\}_{i=1}^N$ for J_i of (3.29) is an open cover of $\mathcal{P}_1(\delta_0)$.

To the set $\mathcal{P}_0(\delta_0)$ we associate the open set

$$J_0 = (-\infty, \delta_0) \cup (\delta_0, +\infty) \subset \mathbb{R}. \quad (3.30)$$

Therefore, the collection of intervals $\{J_i, i = \overline{0, N}\}$ is an open cover of \mathbb{R} .

We construct the partition of unity $\{\xi_i\}_{i=0}^N$ on \mathbb{R} as follows:

$$\xi_i(s) = \xi_i(|s|) = \frac{1}{2}(\tilde{\xi}_i(s) + \tilde{\xi}_i(-s)), \quad s \in \mathbb{R}, \quad (3.31)$$

$$\text{supp } \xi_i \subset J_i, \quad i = \overline{0, N}, \quad (3.32)$$

where $\{\tilde{\xi}_i\}_{i=0}^N$ is a partition of unity for the open cover $\{J_i\}_{i=0}^N$ (see Section 2, Partition of unity, for $U_i = J_i$).

Properties (3.14), (3.32) follow from (2.11) for $\{\tilde{\xi}_i\}_{i=0}^N$ (with $U_i = J_i$), the symmetry of $J_i = \mathcal{J}_{s_i, \varepsilon_i}$, $i = \overline{1, N}$, choice of J_0 in (3.30) and from (3.31).

In addition, (3.15) follows from (3.30) and the construction of $J_i, i = \overline{1, N}$, from (3.29) (see the proof of Lemma 3 and properties (3.29) in Section 7 for details).

Properties (3.17)-(3.20) follow from (3.29) for $\delta = \delta_0$ and from (3.30)-(3.32).

4 Extension to the case of $R_W^{d,2}$

We consider the weighted Radon transforms $R_W^{d,2}$ along two-dimensional planes in \mathbb{R}^d , defined by

$$R_W^{d,2} f(P) = \int_P W(x, P) f(x) dx, \quad P \in \mathcal{P}^{d,2}, \quad x \in P, \quad d \geq 3, \quad (4.1)$$

where $W = W(x, P)$ is the weight, $f = f(x)$ is a test function on \mathbb{R}^d ,

$$\mathcal{P}^{d,2} \text{ is the manifold of all oriented two-dimensional planes } P \text{ in } \mathbb{R}^d. \quad (4.2)$$

Note that the transform $R_W^{d,2}$ is reduced to R_W of (1.1) for $d = 3$.

We say that W in (4.1) is rotation invariant if and only if

$$W(x, P) = \tilde{U}(|x|, \text{dist}(P, \{0\})), \quad (4.3)$$

$$\tilde{U}(r, s) = \tilde{U}(r, -s), \quad \tilde{U}(r, s) = \tilde{U}(-r, s), \quad r \in \mathbb{R}, \quad s \in \mathbb{R}, \quad (4.4)$$

where \tilde{U} is some positive and continuous function on $\mathbb{R} \times \mathbb{R}$, $\text{dist}(P, \{0\})$ denotes the distance from the origin $\{0\} \in \mathbb{R}^d$ to the plane P . Note that $W(x, P)$ is independent of the orientation of P in this case.

Consider \tilde{U} and \tilde{f} such that

$$W(x, \theta) = \tilde{U}(|x|, |x\theta|), \quad f(x) = \tilde{f}(|x|), \quad x \in \mathbb{R}^3, \quad \theta \in \mathbb{S}^2, \quad (4.5)$$

for W and f of Theorem 1 of Section 3.

Theorem 1 implies the following corollary:

Corollary 1. *Let W and f be defined as*

$$W(x, P) = \tilde{U}(|x|, \text{dist}(P, \{0\})), \quad P \in \mathcal{P}^{d,2}, \quad x \in P, \quad (4.6)$$

$$f(x) = \tilde{f}(|x|), \quad x \in \mathbb{R}^d, \quad (4.7)$$

where \tilde{U}, \tilde{f} are the functions of (4.5), $d > 3$. Then

$$R_W^{d,2} f \equiv 0 \text{ on } \mathcal{P}^{d,2}. \quad (4.8)$$

In addition, the weight W is continuous strictly positive and rotation invariant, f is infinitely smooth compactly supported on \mathbb{R}^d and $f \not\equiv 0$.

Formula (4.8) is proved as follows:

$$R_W^{d,2}(P) = \int_P \tilde{U}(|x|, \text{dist}(P, \{0\})) \tilde{f}(|x|) dx = I \stackrel{\text{def}}{=} \int_{P'} \tilde{U}(|x|, s) \tilde{f}(|x|) dx, \quad (4.9)$$

$$P' = \{se_3 + x_1e_1 + x_2e_2 : x = (x_1, x_2) \in \mathbb{R}^2\}, \quad s = \text{dist}(P, \{0\}),$$

where (e_1, \dots, e_d) is the standard basis in \mathbb{R}^d . In addition, $I = 0$ by Theorem 1.

Properties of W and f mentioned in Corollary 1 follow from definitions (4.6), (4.7) and properties of \tilde{U} and \tilde{f} (arising in Theorem 1).

5 Proofs of Lemma 1 and formula (3.13)

5.1 Proof of Lemma 1

The spherical symmetry of f follows from (3.2), (3.3).

The series in (3.2) converges uniformly with all derivatives of f_k . Therefore, $f \in C^\infty(\mathbb{R}^3)$. Due to (3.2), (3.3), (3.4), (3.5) we have that $\text{supp } f_k \subset B$, $k \geq 1$. Therefore, $\text{supp } f \subseteq \overline{B}$.

It remains to show that f restricted to any straight line l in \mathbb{R}^3 intersecting B changes the sign. This implies change of the sign for $f|_P$ for any plane P such that $P \cap B \neq \emptyset$.

We consider

$$D_k = \{x \in \mathbb{R}^3 : |x| \in (1 - 2^{-k}(6/5), 1 - 2^{-k}(4/5))\}, \quad k \geq 1, \quad (5.1)$$

$$l(x_0, \omega) = \{x \in \mathbb{R}^3 : x = x(t) = x_0 + \omega t, t \in \mathbb{R}\}, \quad \omega \in \mathbb{S}^2, \quad x_0 \in \mathbb{R}^3, \quad x_0 \omega = 0. \quad (5.2)$$

Note that $\text{supp } f_k = \overline{D}_k \subset B$. Note also that the line $l(x_0, \omega)$ intersects B if and only if $|x_0| < 1$.

Assuming that

$$|x_0| < 1 - 2^{-k}(6/5), \quad (5.3)$$

we consider $D_k \cap l(x_0, \omega) = I_k^- \sqcup I_k^+$ (see Figure 1):

$$I_k^- = \{x(t) : t \in (-t_1, -t_0)\}, \quad (5.4)$$

$$I_k^+ = \{x(t) : t \in (t_0, t_1)\}, \quad (5.5)$$

$$t_0 := t_0(k), \quad t_1 := t_1(k).$$

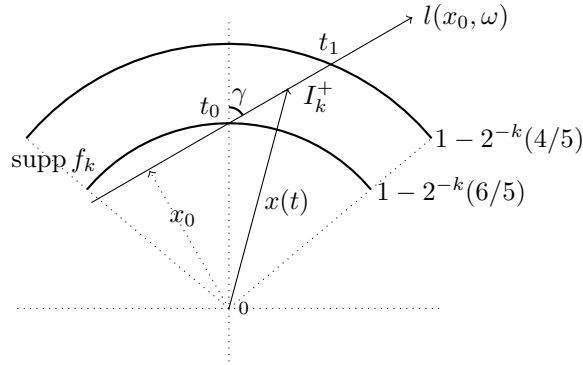


Figure 1.

One can see that assumption (5.3) holds for all $k \geq k_0(|x_0|) = -\ln(\frac{5}{6}(1 - |x_0|))$.

By the Cosine theorem we have (see Figure 1):

$$\varphi(t) := |x(t)|^2 = (t - t_0)^2 + |x(t_0)|^2 - 2|x(t_0)|(t - t_0) \cos(\pi - \gamma) \text{ for } t \in [t_0, t_1]. \quad (5.6)$$

One can see also that

$$\gamma \in [0, \pi/2], \cos(\pi - \gamma) \leq 0. \quad (5.7)$$

Let

$$g_k(t) := \cos(8^k \varphi(t)), t \in [t_1, t_2], \quad (5.8)$$

where $\varphi(t)$ is defined in (5.6).

It is sufficient to show that g_k changes the sign on (t_0, t_1) for sufficiently large k .

Due to (3.2)-(3.5) this implies that f changes the sign on I_k^+ .

From (5.6), (5.7) we obtain the inequality

$$\varphi'(t) = 2(t - t_0) - 2|x(t_0)| \cos(\pi - \gamma) \geq 0 \text{ for } t \in (t_0, t_1), \gamma \in [0, \pi/2], \quad (5.9)$$

which implies the phase in (5.8) is monotonously increasing on $t \in (t_0, t_1)$.

The full variation $V_{(t_0, t_1)}(\varphi)$ of the monotonous phase $\varphi(t)$ on (t_0, t_1) is given by the formula

$$V_{(t_0, t_1)}(\varphi) = (t_1 - t_0)^2 - 2|x(t_0)|(t_1 - t_0) \cos(\pi - \gamma). \quad (5.10)$$

From (5.7), (5.10) we obtain the following inequality

$$V_{(t_0, t_1)}(\varphi) \geq (t_1 - t_0)^2. \quad (5.11)$$

From (5.8), (5.11) it follows that g_k changes the sign on $t \in (t_0, t_1)$, for example, if

$$8^k V_{(t_0, t_1)}(\varphi) \geq 2\pi \text{ or } (t_1 - t_0) \geq \sqrt{2\pi} 4^{-k}. \quad (5.12)$$

On the other hand, $(t_1 - t_0)$ is exactly the length of the segment I_k^+ (see Figure 1). Therefore,

$$(t_1 - t_0) \geq (2/5)2^{-k}. \quad (5.13)$$

Inequality (5.13) implies that (5.12) holds for $k \geq 3$. Therefore, g_k of (5.8) changes the sign on (t_0, t_1) starting from $k \geq \max(3, k_0(|x_0|))$.

Lemma 1 is proved.

5.2 Proof of formula (3.13)

From (1.1), (3.2)-(3.5), (3.21), (3.24), (3.25) it follows that:

$$R_{W_0} f(s, \theta) = \int_{x\theta=s} f(x) dx - G(s\theta, \theta) \sum_{k=3}^{\infty} k! \psi_{k-2}(|s|) \frac{\int f(x) f_k(x) dx}{H_k(s\theta, \theta)} \quad (5.14)$$

$$= \int_{x\theta=s} f(x) dx - \int_{x\theta=s} f(x) dx \sum_{k=3}^{\infty} \psi_{k-2}(|s|) \frac{\int f_k^2(x) dx}{\int_{x\theta=s} f_k^2(x) dx} \quad (5.15)$$

$$= \int_{x\theta=s} f(x) dx - \int_{x\theta=s} f(x) dx \sum_{k=3}^{\infty} \psi_{k-2}(|s|) = 0, |s| > 1/2, \theta \in \mathbb{S}^2. \quad (5.16)$$

Formula (3.13) is proved.

6 Proof of Lemma 2

Let

$$\Lambda_k := \{(x, \theta) \in \mathbb{R}^3 \times \mathbb{S}^2 : |x\theta| \in (1 - 2^{-k+3}, 1 - 2^{-k+1})\}, k \in \mathbb{N}, k \geq 4. \quad (6.1)$$

From (3.21) it follows that, for $k \geq 4$:

$$\text{supp } \psi_{k-1} \subset (1 - 2^{-k+2}, 1 - 2^{-k}), \quad (6.2)$$

$$\text{supp } \psi_{k-2} \subset (1 - 2^{-k+3}, 1 - 2^{-k+1}), \quad (6.3)$$

$$\text{supp } \psi_{k-3} \subset (1 - 2^{-k+4}, 1 - 2^{-k+2}). \quad (6.4)$$

Formulas (3.24), (3.25), (6.2)-(6.4) imply the following expression for $W_0(x, \theta)$:

$$W_0(x, \theta) = 1 - G(x, \theta) \left((k-1)! f_{k-1}(x) \frac{\psi_{k-3}(|x\theta|)}{H_{k-1}(x, \theta)} + k! f_k(x) \frac{\psi_{k-2}(|x\theta|)}{H_k(x, \theta)} + (k+1)! f_{k+1}(x) \frac{\psi_{k-1}(|x\theta|)}{H_{k+1}(x, \theta)} \right), (x, \theta) \in \Lambda_k, k \geq 4. \quad (6.5)$$

Lemma 4. *There are positive constants c_1, c_2, k_1 depending on Φ , such that*

$$|f_k(x)| \leq c_1, \text{ for } k \in \mathbb{N}, \quad (6.6)$$

$$\left| \frac{\psi_{k-2}(|x\theta|)}{H_k(x, \theta)} \right| \leq c_2 2^k \quad \text{for } k \geq k_1 \text{ and } |x\theta| \leq 1 - 2^{-k+1}, \quad (6.7)$$

$$|G(x, \theta)| \leq c_1 \frac{4^{-k}}{k!} \quad \text{for } k \geq 3 \text{ and } |x\theta| \geq 1 - 2^{-k}, \quad (6.8)$$

$$x \in \mathbb{R}^3, \theta \in \mathbb{S}^2, 1/2 < |x\theta| < 1,$$

where f_k, G, H_k are defined in (3.3), (3.25).

Lemma 4 is proved in Section 8.

From definition (6.1) and estimates (6.7), (6.8) it follows that

$$|G(x, \theta)| \leq c_1 4^{-k+3}/(k-3)!, \quad (6.9)$$

$$\left| \frac{\psi_{k-2}(|x\theta|)}{H_k(x, \theta)} \right| \leq c_2 2^k, \quad (6.10)$$

for $(x, \theta) \in \Lambda_k, k \geq \max(4, k_1)$.

In addition, properties (6.2)-(6.4) and estimate (6.7) imply that:

$$\begin{cases} \psi_{k-1}(|x\theta|) = 0, \\ \left| \frac{\psi_{k-3}(|x\theta|)}{H_{k-1}(x, \theta)} \right| \leq c_2 2^{k-1} \end{cases} \quad \text{if } |x\theta| \in (1 - 2^{-k+3}, 1 - 2^{-k+2}), \quad (6.11)$$

$$\begin{cases} \psi_{k-2}(|x\theta|) = 0, \\ \left| \frac{\psi_{k-1}(|x\theta|)}{H_{k+1}(x, \theta)} \right| \leq c_2 2^{k+1} \end{cases} \quad \text{if } |x\theta| \in (1 - 2^{-k+2}, 1 - 2^{-k+1}), \quad (6.12)$$

$$\begin{cases} \psi_{k-1}(|x\theta|) = 0, \\ \psi_{k-3}(|x\theta|) = 0 \end{cases} \quad \text{if } |x\theta| = 1 - 2^{-k+2}, \quad (6.13)$$

for $(x, \theta) \in \Lambda_k, k \geq \max(4, k_1)$.

Note that the condition $(x, \theta) \in \Lambda_k$ is splitted into the assumptions of (6.11), (6.12), (6.13).

Due to formulas (6.5), (6.9)-(6.13), we obtain the following estimates:

$$\begin{aligned} |1 - W_0(x, \theta)| &= |G(x, \theta)| \left| (k-1)! f_{k-1}(x) \frac{\psi_{k-3}(|x\theta|)}{H_{k-1}(x, \theta)} + k! f_{k-2}(x) \frac{\psi_{k-2}(|x\theta|)}{H_k(x, \theta)} \right| \\ &\leq c_1 4^{-k+3} (c_1 c_2 (k-2)(k-1) 2^{k-1} + c_1 c_2 (k-2)(k-1) k 2^k) \\ &\leq 2^6 c_1^2 c_2 2^{-k} k^3 \quad \text{if } |x\theta| \in (1 - 2^{-k+3}, 1 - 2^{-k+2}), \end{aligned} \quad (6.14)$$

$$\begin{aligned} |1 - W_0(x, \theta)| &= |G(x, \theta)| \left| k! f_k(x) \frac{\psi_{k-2}(|x\theta|)}{H_k(x, \theta)} + (k+1)! f_{k+1}(x) \frac{\psi_{k-1}(|x\theta|)}{H_{k+1}(x, \theta)} \right| \\ &\leq c_1 4^{-k+3} (c_1 c_2 2^k (k-1)(k-2) + c_1 c_2 2^{k+1} (k-2)(k-1) k (k+1)) \\ &\leq 2^{12} c_1^2 c_2 2^{-k} k^4 \quad \text{if } |x\theta| \in (1 - 2^{-k+2}, 1 - 2^{-k+1}), \end{aligned} \quad (6.15)$$

$$\begin{aligned} |1 - W_0(x, \theta)| &= |G(x, \theta)| \left| k! f_k(x) \frac{\psi_{k-2}(|x\theta|)}{H_k(x, \theta)} \right| \\ &\leq 2^6 c_1^2 c_2 2^{-k} k^3 \quad \text{if } |x\theta| = 1 - 2^{-k+2}. \end{aligned} \quad (6.16)$$

Estimates (6.14)-(6.16) imply that

$$|1 - W_0(x, \theta)| \leq C \cdot 2^{-k} k^4, \quad (x, \theta) \in \Lambda_k, k \geq \max(4, k_1). \quad (6.17)$$

where C is a positive constant depending on c_1, c_2 of Lemma 4.

In addition, for $(x, \theta) \in \Lambda_k$ we have that $2^{-k+1} < \rho(|x\theta|) < 2^{-k+3}$, which together with (6.17) imply (3.26).

Lemma 2 is proved.

7 Proof of Lemma 3

Let (e_1, e_2) be an orthonormal basis on $P_{(s, \theta)} \in \mathcal{P}$ and the origin of the coordinate system on $P_{(s, \theta)}$ is located at $s\theta \in P_{(s, \theta)}$.

By $u = (u_1, u_2), u \in \mathbb{R}^2$, we denote the coordinates on $P_{(s, \theta)}$ with respect to (e_1, e_2) .

Using Lemma 1 one can see that

$$f|_{P_{(s,\theta)}} \in C_0^\infty(\mathbb{R}^2), f|_{P_{(s,\theta)}}(u) = f|_{P_{(s,\theta)}}(|u|), u \in \mathbb{R}^2. \quad (7.1)$$

By our assumptions $f|_{P_{(s_0,\theta_0)}}(u)$ changes the sign.

Using this assumption and (7.1) one can see that there exist $\psi_{1,s_0}, \psi_{2,s_0}$, such that:

$$\psi_{1,s_0} \in C([0, +\infty)), \psi_{1,s_0} \geq 0, \psi_{2,s_0}(u) := \psi_{1,s_0}(|u|), u \in \mathbb{R}^2, \quad (7.2)$$

$$\int_{P_{(s_0,\theta_0)}} f \psi_{2,s_0} d\sigma \neq 0. \quad (7.3)$$

and if

$$\int_{P_{(s_0,\theta_0)}} f d\sigma \neq 0 \quad (7.4)$$

then also

$$\operatorname{sgn}\left(\int_{P_{(s_0,\theta_0)}} f d\sigma\right) \operatorname{sgn}\left(\int_{P_{(s_0,\theta_0)}} f \psi_{2,s_0} d\sigma\right) = -1, \quad (7.5)$$

where $d\sigma = du_1 du_2$ (i.e., σ is the standard Euclidean measure on $P_{(s,\theta)}$).

Let

$$W_{f,s_0}(x, \theta) = 1 - \psi_{1,s_0}(|x - (x\theta)\theta|) \frac{\int_{P_{(x\theta,\theta)}} f d\sigma}{\int_{P_{(x\theta,\theta)}} f \psi_{2,s_0} d\sigma}, x \in \mathbb{R}^3, \theta \in \mathbb{S}^2, \quad (7.6)$$

where $d\sigma = du_1 du_2$ and (u_1, u_2) are the coordinates on $P_{(s,\theta)}$, $s = x\theta$, defined at the beginning of this proof.

Results of Lemma 1 and property (7.2) imply that

$$\int_{P_{(x\theta,\theta)}} f d\sigma \text{ and } \int_{P_{(x\theta,\theta)}} f \psi_{2,s_0} d\sigma \text{ depend only on } |x\theta|, \text{ where } x \in \mathbb{R}^3, \theta \in \mathbb{S}^2. \quad (7.7)$$

From (7.6), (7.7) it follows that W_{f,s_0} is rotation-invariant in the sense (1.3), (1.4).

Formulas (7.3), (7.6), (7.7) and properties of f and ψ_{2,s_0} of Lemma 1 and (7.2) imply that

$$\exists \varepsilon_1 > 0 : \int_{P_{(x\theta,\theta)}} f \psi_{2,s_0} d\sigma \neq 0, \text{ for } (x, \theta) \in \Omega(\mathcal{J}_{s_0, \varepsilon_1}), \quad (7.8)$$

where the sets $\mathcal{J}_{s,\varepsilon}, \Omega(\mathcal{J})$ are defined in (2.6), (2.7), respectively.

In addition, using (7.6), (7.8), one can see that

$$W_{f,s_0} \text{ is continuous on } (x, \theta) \in \Omega(\mathcal{J}_{s_0, \varepsilon_1}). \quad (7.9)$$

In addition, from (7.1)-(7.7) it follows that

$$\begin{aligned} \text{if } |x\theta| = |s_0| \text{ then } W_{f,s_0}(x, \theta) &= 1 - \psi_{1,s_0}(|x - (x\theta)\theta|) \frac{\int_{P_{(s_0,\theta)}} f d\sigma}{\int_{P_{(s_0,\theta)}} f \psi_{2,s_0} d\sigma} \\ &= 1 - \psi_{1,s_0}(|x - (x\theta)\theta|) \frac{\int_{P_{(s_0,\theta_0)}} f d\sigma}{\int_{P_{(s_0,\theta_0)}} f \psi_{2,s_0} d\sigma} \geq 1. \end{aligned} \quad (7.10)$$

From properties of $f, \psi_{1,s_0}, \psi_{2,s_0}$ of Lemma 1 and (7.2) and from formulas (7.6), (7.7), (7.9), (7.10) it follows that

$$\exists \varepsilon_0 > 0 (\varepsilon_0 < \varepsilon_1) : W_{f,s_0}(x, \theta) \geq 1/2, \text{ for } (x, \theta) \in \Omega(\mathcal{J}_{s_0, \varepsilon_0}), \quad (7.11)$$

which implies strict positiveness for W_{f,s_0} on $\Omega(\mathcal{J}_{s_0, \varepsilon})$.

Properties (7.7), (7.9), (7.11) imply item (ii) of Lemma 3 for $W_{f,s_0,\varepsilon} := W_{f,s_0}$, defined on $\Omega(\mathcal{J}_{s_0, \varepsilon_0})$.

From (1.1), (7.6), (7.8) it follows that

$$\begin{aligned} R_{W_{f,s_0}} f(s, \theta) &= \int_{P_{(s,\theta)}} W_{f,s_0}(\cdot, \theta) f d\sigma \\ &= \int_{P_{(s,\theta)}} f d\sigma - \frac{\int_{P_{(s,\theta)}} f d\sigma}{\int_{P_{(s,\theta)}} f \psi_{2,s_0} d\sigma} \int_{P_{(s,\theta)}} f \psi_{2,s_0} d\sigma = 0 \text{ for } s \in \mathcal{J}_{s_0, \varepsilon_0}, \theta \in \mathbb{S}^2. \end{aligned} \quad (7.12)$$

Item (i) of Lemma 3 follows from (7.12).

Lemma 3 is proved.

8 Proof of Lemma 4

8.1 Proof of estimate (6.6)

Estimate (6.6) follows from (3.3) and properties (3.4)-(3.6).

8.2 Proof of estimate (6.8)

From definitions (3.2), (3.25) we have that

$$G = \sum_{k=1}^{\infty} \frac{G_k}{k!}, \quad (8.1)$$

$$G_k(x, \theta) = \int_{y\theta=x\theta} f_k(y) dy, \quad x \in \mathbb{R}^3, \theta \in \mathbb{S}^2. \quad (8.2)$$

Parametrization of the points $y(r, \phi)$ on $P_{(s, \theta)} \in \mathcal{P}$, $s \in \mathbb{R}$, $\theta \in \mathbb{S}^2$, is given by the formula

$$y(r, \phi) = s\theta + r(e_1 \cos \phi + e_2 \sin \phi), \quad r \in [0, +\infty), \phi \in [0, 2\pi], \quad (8.3)$$

where (e_1, e_2) is some fixed orthonormal basis on $P_{(s, \theta)}$.

On the other hand,

$$r = r(\gamma) = |s| \tan(\gamma), \quad \gamma \in [0, \pi/2), \quad (8.4)$$

where γ is the angle between $s\theta$ and the radius-vector $y(r, \phi)$ of (8.3).

It is convenient to rewrite $y(r, \phi)$ of (8.3) as $y = y(r(\gamma), \phi) \stackrel{def}{=} y(\gamma, \phi)$, $\gamma \in [0, \pi/2)$, $\phi \in [0, 2\pi]$.

The standard Lebesgue measure σ on $P_{(s, \theta)}$ is given by the following formula:

$$\begin{aligned} d\sigma(\gamma, \phi) &= r(\gamma, \phi) d\phi dr(\gamma) = |s| \tan \gamma d\phi dr(\gamma) \\ &= |s|^2 \frac{\sin \gamma}{\cos^3 \gamma} d\phi d\gamma. \end{aligned} \quad (8.5)$$

From (3.3), (8.2)-(8.5) we obtain

$$\begin{aligned} G_k(x, \theta) &= s^2 \int_0^{2\pi} d\phi \int_0^{\pi/2} \Phi \left(2^k \left(1 - \frac{|s|}{\cos \gamma} \right) \right) \cos \left(8^k \frac{|s|^2}{\cos^2 \gamma} \right) \frac{\sin \gamma}{\cos^3 \gamma} d\gamma \\ &= -2\pi |s|^2 \int_0^{\pi/2} \Phi \left(2^k \left(1 - \frac{|s|}{\cos \gamma} \right) \right) \cos \left(8^k \frac{|s|^2}{\cos^2 \gamma} \right) \frac{d(\cos \gamma)}{\cos^3 \gamma} \\ &= \{t = \cos \gamma\} = -2\pi |s|^2 \int_1^0 \Phi \left(2^k \left(1 - \frac{|s|}{t} \right) \right) \cos \left(8^k \frac{|s|^2}{t^2} \right) \frac{dt}{t^3} \\ &= \{u = \frac{1}{t^2}\} = \pi |s|^2 \int_1^{+\infty} \Phi(2^k(1 - |s|\sqrt{u})) \cos(8^k |s|^2 u) du, \quad s = x\theta. \end{aligned} \quad (8.6)$$

From (3.4)-(3.6), (8.6) it follows that

$$\begin{aligned} G_k(x, \theta) &= 8^{-k} \pi \int_1^{+\infty} \Phi(2^k(1 - |s|\sqrt{u})) d(\sin(8^k |s|^2 u)) \\ &= 8^{-k} \pi \left(-\Phi(2^k(1 - |s|)) \sin(8^k |s|^2) - \int_1^{+\infty} \left(\frac{d}{du} \Phi(2^k(1 - |s|\sqrt{u})) \right) \sin(8^k |s|^2 u) du \right), \end{aligned} \quad (8.7)$$

$$|\Phi(2^k(1 - |s|)) \sin(8^k |s|^2)| \leq 1, \quad (8.8)$$

$$\begin{aligned} \left| \int_1^{+\infty} \left(\frac{d}{du} \Phi(2^k(1 - |s|\sqrt{u})) \right) \sin(8^k |s|^2 u) du \right| &\leq 2^k \max_{t \in \mathbb{R}} |\Phi'(t)| \int_{\Lambda_{k, |s|}} du \\ &\leq 2^k \max_{t \in \mathbb{R}} |\Phi'(t)|, \end{aligned} \quad (8.9)$$

$$\Lambda_{k, |s|} = \{u \geq 1 : 2^k(1 - |s|\sqrt{u}) \in [4/5, 6/5]\}, \quad (8.10)$$

where $1/2 < |s| < 1$, $s = x\theta$, $k \in \mathbb{N}$.

Note that

$$|\Lambda_{k, |s|}| \leq 1 \text{ for } 1/2 < |s| < 1, \quad (8.11)$$

where $|\Lambda|$ denotes the length of Λ .

Formulas (8.7)-(8.11) imply that

$$|G_k(x, \theta)| \leq 4^{-k} \pi \max_{t \in \mathbb{R}} |\Phi'(t)| \text{ for } 1/2 < |s| < 1, s = x\theta, k \in \mathbb{N}. \quad (8.12)$$

Note that for $y \in P_{(s, \theta)}$, the following inequality holds:

$$2^k(1 - |y|) \leq 2^k(1 - |s|) \leq 2^{k-m} \leq 4/5 \text{ for } 1 - 2^{-m} \leq |s| < 1, k < m, m \geq 3. \quad (8.13)$$

Formulas (3.3), (3.4), (8.13) imply that

$$P_{(s, \theta)} \cap \text{supp } f_k = \emptyset \text{ if } |s| \geq 1 - 2^{-m}, k < m. \quad (8.14)$$

In turn, (8.2), (8.14) imply that

$$G_k(x, \theta) = 0 \text{ for } k < m, |x\theta| \geq 1 - 2^{-m}. \quad (8.15)$$

Due to (8.1), (8.12), (8.15) we have that:

$$\begin{aligned} |G(x, \theta)| &\leq \sum_{k=1}^{\infty} |G_k(x, \theta)|/k! = \sum_{k=m}^{\infty} |G_k(x, \theta)|/k! \\ &\leq \max_{t \in \mathbb{R}} |\Phi'(t)| \pi 4^{-m}/m! \sum_{k=0}^{\infty} 4^{-k} = c_1 \frac{4^{-m}}{m!}, c_1 = \frac{4\pi}{3} \max_{t \in \mathbb{R}} |\Phi'(t)| \\ &\text{for } |x\theta| \geq 1 - 2^{-m}, m \geq 3. \end{aligned} \quad (8.16)$$

Estimate (6.8) follows from (8.16).

8.3 Proof of estimate (6.7)

For each ψ_k from (3.21) we have that:

$$|\psi_k| \leq 1. \quad (8.17)$$

Therefore, it is sufficient to show that

$$H_k \geq C_2 2^{-k} \text{ for } k \geq k_1, C_2 = c_2^{-1}. \quad (8.18)$$

Due to formula (3.25) and in a similar way with (8.6) we obtain

$$H_k(x, \theta) = |s|^2 \pi \int_1^{\infty} \Phi^2(2^k(1 - |s|\sqrt{u})) \cos^2(8^k |s|^2 u) du = H_{k,1}(x, \theta) + H_{k,2}(x, \theta), s = x\theta, \quad (8.19)$$

$$H_{k,1}(x, \theta) = \frac{\pi |s|^2}{2} \int_1^{+\infty} \Phi^2(2^k(1 - |s|\sqrt{u})) du, \quad (8.20)$$

$$H_{k,2}(x, \theta) = \frac{\pi |s|^2}{2} \int_1^{+\infty} \Phi^2(2^k(1 - |s|\sqrt{u})) \cos(2 \cdot 8^k |s|^2 u) du. \quad (8.21)$$

Note that

$$2^k(1 - |s|) \geq 2^k \cdot 2^{-k+1} \geq 2 > 6/5 \text{ for } |s| \leq 1 - 2^{-k+1}, k \geq 3. \quad (8.22)$$

In turn, (3.4), (8.22) imply that

$$\Phi(2^k(1 - |s|\sqrt{u})) = 0 \text{ for } u \leq 1, |s| \leq 1 - 2^{-k+1}, k \geq 3. \quad (8.23)$$

Using (8.22) one can see that

$$\exists u_1 \geq 1, u_2 \geq 1, u_2 > u_1 \text{ such that } \begin{cases} 2^k(1 - |s|\sqrt{u_1}) = 11/10, \\ 2^k(1 - |s|\sqrt{u_2}) = 9/10, \end{cases} \quad (8.24)$$

$$|u_2 - u_1| \geq (\sqrt{u_2} - \sqrt{u_1}) = \frac{2^{-k}}{5} |s|^{-1} \geq \frac{2^{-k}}{5}, \quad (8.25)$$

$$\text{for } 1/2 < |s| \leq 1 - 2^{-k+1}, k \geq 3.$$

Using (3.4), (3.6), (8.20), (8.23), (8.25) we obtain

$$H_{k,1}(x, \theta) \geq \frac{\pi}{8} \int_{u_1}^{u_2} du \geq 2^{-k} \frac{\pi}{40}, \text{ for } 1/2 < |x\theta| < 1 - 2^{-k+1}, k \geq 3. \quad (8.26)$$

On the other hand, using (3.4), (8.21), (8.23), in a similar way with (8.7)-(8.11), we obtain

$$\begin{aligned}
|H_{k,2}(x, \theta)| &= \frac{\pi |s|^2}{2} \left| \int_1^{+\infty} \Phi^2(2^k(1 - |s|\sqrt{u})) \cos(2 \cdot 8^k |s|^2 u) du \right| \\
&= \frac{\pi}{4} 8^{-k} |s|^{-2} \left| \int_1^{+\infty} \sin(2 \cdot 8^k |s|^2 u) \left(\frac{d}{du} \Phi^2(2^k(1 - |s|\sqrt{u})) \right) du \right| \\
&\leq \frac{\pi}{4} 8^{-k} |s|^{-1} \max_{t \in \mathbb{R}} |\Phi(t)| \cdot \max_{t \in \mathbb{R}} |\Phi'(t)| \cdot 2^k \int_{\Lambda_{k,|s|}} du \\
&\leq \frac{\pi}{2} 4^{-k} \max_{t \in \mathbb{R}} |\Phi(t)| \cdot \max_{t \in \mathbb{R}} |\Phi'(t)|, \quad s = x\theta,
\end{aligned} \tag{8.27}$$

for $1/2 < |x\theta| < 1 - 2^{-k+1}$, $k \geq 3$.

From (8.19)-(8.21), (8.26), (8.27) it follows that

$$\begin{aligned}
|H_k(x, \theta)| &\geq |H_{k,1}(x, \theta)| - |H_{k,2}(x, \theta)| \\
&\geq \frac{\pi}{40} 2^{-k} - \frac{\pi}{2} 4^{-k} \max_{t \in \mathbb{R}} |\Phi(t)| \cdot \max_{t \in \mathbb{R}} |\Phi'(t)| \\
&\geq C_2 2^{-k} \quad \text{for } 1/2 < |x\theta| < 1 - 2^{-k+1}, \quad k \geq k_1, \\
C_2 &= \frac{\pi}{40} - 2^{-k_1} \frac{\pi}{2} \max_{t \in \mathbb{R}} |\Phi(t)| \max_{t \in \mathbb{R}} |\Phi'(t)|,
\end{aligned} \tag{8.28}$$

where k_1 is arbitrary constant such that $k_1 \geq 3$ and C_2 is positive.

Estimate (6.7) follows from (8.28).

Lemma 4 is proved.

Aknowledgements

This work is partially supported by the PRC n° 1545 CNRS/RFBR: Équations quasi-linéaires, problèmes inverses et leurs applications.

References

- [Bey84] Beylkin, G., The inversion problem and applications of the generalized Radon transform. *Communications on pure and applied mathematics*, 37(5) : 579-599, 1984.
- [Bey85] Beylkin, G., Imaging of discontinuities in the inverse scattering problem by inversion of a causal generalized Radon transform *Journal of Mathematical Physics*, 26(1) : 99-108, 1985.
- [BQ87] Boman, J., Quinto, E.T., Support theorems for real-analytic Radon transforms. *Duke Mathematical J.*, 55(4):943-948, 1987.
- [Bom93] Boman, J., An example of non-uniqueness for a generalized Radon transform. *Journal d'Analyse Mathématique*, 61(1):395-401, 1993.
- [MCar92] Do Carmo, M. P., Riemannian Geometry. Birkhäuser Basel, 1992.
- [Fi86] Finch, D., Uniqueness for the attenuated X-ray transform in the physical range. *Inverse problems*, 2(2), 1986.
- [GN16] Goncharov, F.O., Novikov, R.G., An analog of Chang inversion formula for weighted Radon transforms in multidimensions. *Eurasian Journal of Mathematical and Computer Applications*, 4(2):23-32, 2016.
- [Gon17] Goncharov, F.O., An iterative inversion of weighted Radon transforms along hyperplanes. *arXiv:1611.10209v8*, 2017.
- [GN17] Goncharov, F.O., Novikov, R.G., An example of non-uniqueness for the weighted Radon transforms along hyperplanes in multidimensions. *arXiv:1709.04194v2*, 2017.
- [GonNov17] Goncharov, F.O., Novikov, R.G., An example of non-uniqueness for weighted ray transforms in multidimensions. (in preparation)
- [GuiNov14] Guillement, J.-P., Novikov, R.G., Inversion of weighted Radon transforms via finite Fourier series weight approximations. *Inverse Problems in Science and Engineering*, 22(5):787-802, 2014.
- [Kun92] Kunyansky, L., Generalized and attenuated Radon transforms: restorative approach to the numerical inversion. *Inverse Problems*, 8(5):809, 1992.
- [MQ85] Markoe, A., Quinto, E.T., An elementary proof of local invertibility for generalized and attenuated Radon transforms. *SIAM Journal on Mathematical Analysis*, 16(5):1114-1119, 1985.

- [FNatt01] Natterer, F. *The Mathematics of Computerized Tomography*. SIAM, 2001.
- [Nov11] Novikov, R.G., Weighted Radon transforms for which Chang's approximate inversion formula is exact. *Russian Mathematical Surveys*, 66(2):442–443, 2011.
- [Nov14] Novikov, R.G., Weighted Radon transforms and first order differential systems on the plane. *Moscow Mathematical Journal*, 14(4):807–823, 2014.
- [Qui83] Quinto, E.T., The invertibility of rotation invariant Radon transforms. *Journal of Mathematical Analysis and Applications*, 91(2):510–522, 1983.
- [Qui83Err] Quinto, E.T., The invertibility of rotation invariant Radon transforms. Erratum. *Journal of Mathematical Analysis and Applications*, 94(2):602-603, 1983.