

INSTRUCTIONS FOR CONTRIBUTORS

Editorial Policy

The journal welcomes high quality contributions on topics closely related to dynamical systems and ergodic theory. Submissions in the field of differential geometry, number theory, operator algebra, differential, topological, symbolic, measurable dynamics and celestial and statistical mechanics are especially welcome. Expository survey papers and reviews of relevant books will be published from time to time.

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The first page must include the title, the author’s name and institution, an abstract of up to 250 words, 3–5 Keywords and 2020 Mathematics Subject Classification codes with a distinction between Primary and Secondary codes.

The title, while brief, must be informative (e.g. ‘A new proof of the ergodic theorem’, whereas ‘Some applications of a theorem of Birkhoff’ would be useless).

Notation

Avoid abbreviations such as Thm, Prop., Eq., iff. In the text do not use symbols $\forall$, $\exists$, $\Rightarrow$ and $\Leftrightarrow$. Fractions are generally best expressed by a solidus. Complicated exponents like $\exp\{z^2 \sin \theta / (1 + y^2)\}$ should be shown in this and no other way.

It helps if displayed equations or statements which will be quoted later are numbered in order on the right of their line. They can then be referred to by, for example, ‘from (7)’.

If an author wishes to mark the end of the proof of a theorem, the sign $\square$ may be used.

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References should be collected at the end of the paper numbered in alphabetical order of the author’s names or by order of citation. Include in the list of references only those works that are cited. For the style of references please consult recent issues of the journal. A reference to a book should give the title, in italics, and then in roman type the publisher’s name and the place and year of publication:

[4] N. Dunford and J. T. Schwartz. *Linear Operators*. Part I. Wiley, New York, 1958.

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[6] J. E. Littlewood. The ‘pits effect’ for functions in the unit circle. *J. Analyse Math.* **23** (1970), 236–268.

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Ergodic theory and dynamical systems

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