Project 1

November 22, 2024

Antonio Pampalone 23586519 Giuseppe Pisante 23610012 Martina Raffaelli 23616907



Task 2.0:

The momentum equation is a parabolic equation since, if we compute the $\Delta = B^2 - 4AC$ from the general form of the partial differential equations:

$$A\frac{\partial^2 u}{\partial x^2} + B\frac{\partial^2 u}{\partial x \partial y} + C\frac{\partial^2 u}{\partial y^2} + D\frac{\partial u}{\partial x} + E\frac{\partial u}{\partial y} + Fu + G = 0$$
 (1)

we get $\Delta = 0$, which means that the equation is parabolic.

We now define the additional boundary conditions:

- u(0,y)=1
- u(1,y) = 1
- v(0, y) = 0
- v(1,y) = 0
- $v(x,\infty)=0$

Task 2.1:

The discretization applied to the x-momentum equation takes into account the parabolic nature of the equation. The discretization is performed using the central difference scheme for the y-direction and the backward difference scheme for the x-direction. The discretized equation is as follows:

$$u_{i,j} \frac{u_{i,j} - u_{i-1,j}}{\Delta x} + v_{i,j} \frac{u_{i,j+1} - u_{i,j-1}}{2\Delta y} = \frac{1}{Re} \frac{u_{i,j+1} - 2u_{i,j} + u_{i,j-1}}{\Delta y^2}$$

Such equation is a steady-state equation and thus it doesn't require any time-stepping algorithm. For this reason, the costraints for convergence are only applied on the spatial discretization.

The discretization of the first derivative in the x-direction using the Backward Difference Scheme (BDS) is given by:

$$\frac{\partial u}{\partial x} \approx \frac{u_{i,j} - u_{i-1,j}}{\Delta x}$$

Using Taylor series expansions for u(x) around x_i , we have:

$$u_{i-1,j} = u(x_i - \Delta x) = u(x_i) - \Delta x \frac{\partial u}{\partial x} + \frac{\Delta x^2}{2} \frac{\partial^2 u}{\partial x^2} + O(\Delta x^3)$$

Therefore, the approximation for the derivative becomes

$$\frac{u_{i,j} - u_{i-1,j}}{\Delta x} = \frac{\partial u}{\partial x} + \frac{\Delta x}{2} \frac{\partial^2 u}{\partial x^2} + O(\Delta x^2)$$

The truncation error for the Backward Difference Scheme is:

$$T_{\rm BDS} = -\frac{\Delta x}{2} \frac{\partial^2 u}{\partial x^2} + O(\Delta x^2)$$

The discretization of the second derivative in the y-direction using the Central Difference Scheme (CDS) is given by:

$$\frac{\partial^2 u}{\partial y^2} \approx \frac{u_{i,j+1} - 2u_{i,j} + u_{i,j-1}}{\Delta y^2}$$

Using Taylor series expansions for u(y) around y_j , we have:

$$u_{i,j+1} = u(y_j + \Delta y) = u(y_j) + \Delta y \frac{\partial u}{\partial y} + \frac{\Delta y^2}{2} \frac{\partial^2 u}{\partial y^2} + \frac{\Delta y^3}{6} \frac{\partial^3 u}{\partial y^3} + O(\Delta y^4)$$

$$u_{i,j-1} = u(y_j - \Delta y) = u(y_j) - \Delta y \frac{\partial u}{\partial y} + \frac{\Delta y^2}{2} \frac{\partial^2 u}{\partial y^2} - \frac{\Delta y^3}{6} \frac{\partial^3 u}{\partial y^3} + O(\Delta y^4)$$

Subtracting $2u_{i,j}$ from the sum of $u_{i,j+1}$ and $u_{i,j-1}$, we get:

$$u_{i,j+1} - 2u_{i,j} + u_{i,j-1} = 2 \cdot \frac{\Delta y^2}{2} \frac{\partial^2 u}{\partial y^2} + O(\Delta y^4)$$

Thus, the discretized second derivative becomes:

$$\frac{u_{i,j+1} - 2u_{i,j} + u_{i,j-1}}{\Delta y^2} = \frac{\partial^2 u}{\partial y^2} + O(\Delta y^2)$$

The leading truncation error for the Central Difference Scheme is:

$$T_{\text{CDS}} = \frac{\Delta y^2}{6} \frac{\partial^4 u}{\partial y^4} + O(\Delta y^4)$$

Summary of Truncation Errors

Thus, the sum of the truncation errors is:

$$T_{\text{total}} = T_{\text{BDS}} + T_{\text{CDS}} = -\frac{\Delta x}{2} \frac{\partial^2 u}{\partial x^2} + \frac{\Delta y^2}{6} \frac{\partial^4 u}{\partial y^4} + O(\Delta x^2) + O(\Delta y^4)$$

Task 2.2:

This system is solved using a GMRES iterative solver, which allows us to solve the system for a non-symmetric A and the non linearities of the x-momentum. The solver updates the values of u and v at each iteration, denoted as $u^{(k+1)}$ and $v^{(k+1)}$, by utilizing the values from the previous iteration, $u^{(k)}$ and $v^{(k)}$, to handle the non-linear terms effectively. The system of partial differential equations is: The continuity equation is discretized using the backward difference scheme (BDS) along the x-direction and the central difference scheme (CDS) along the y-direction. The discretized continuity equation is given by:

$$\begin{cases} \frac{u_{i,j} - u_{i-1,j}}{\Delta x} + \frac{v_{i,j+1} - v_{i,j-1}}{2\Delta y} = 0 \\ u_{i,j} \frac{u_{i,j} - u_{i-1,j}}{\Delta x} + v_{i,j} \frac{u_{i,j+1} - u_{i,j-1}}{2\Delta y} = \frac{1}{Re} \frac{u_{i,j+1} - 2u_{i,j} + u_{i,j-1}}{\Delta y^2} \end{cases}$$

To solve this, we construct a linear system of equations in the form $\mathbf{A}\mathbf{x} = \mathbf{b}$, where \mathbf{A} is a $2n^2 \times 2n^2$ matrix, \mathbf{b} is a $2n^2$ vector, and \mathbf{x} is also a $2n^2$ vector. The structure of \mathbf{x} is as follows:

$$\mathbf{x} = \begin{bmatrix} u_{1,1} \\ u_{1,2} \\ \vdots \\ u_{n,n} \\ v_{1,1} \\ v_{1,2} \\ \vdots \\ v_{n,n} \end{bmatrix}$$

The structure of the matrix A is as follows:

$$A = \begin{bmatrix} \frac{1}{\Delta x} & \cdots & -\frac{1}{\Delta x} & \cdots & 0 & \cdots & 0 & \cdots \\ \cdots & \frac{u_{i,j}}{\Delta x} - \frac{2}{Re} \left(\frac{1}{\Delta x^2} + \frac{1}{\Delta y^2} \right) & \cdots & \frac{1}{Re\Delta x^2} & \cdots & 0 & \cdots & 0 & \cdots \\ \vdots & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \vdots & \ddots & \vdots & \ddots & \vdots \\ 0 & \vdots & \ddots & \ddots & \ddots & \vdots \\ 0 & \vdots & \ddots & \ddots & \ddots & \vdots \\ 0 & \vdots & \ddots & \ddots & \ddots & \vdots \\ 0 & \vdots & \ddots & \ddots & \ddots & \vdots \\ 0 & \vdots & \ddots & \ddots & \ddots & \vdots \\ 0 & \vdots & \ddots & \ddots & \ddots & \vdots \\ 0 & \vdots & \ddots & \ddots & \ddots & \vdots \\ 0 & \vdots & \ddots & \ddots & \ddots & \vdots \\ 0 & \vdots & \ddots & \ddots & \ddots & \vdots \\ 0 & \vdots & \ddots & \ddots & \ddots & \vdots \\ 0 & \vdots & \ddots & \ddots & \ddots & \vdots \\ 0 & \vdots & \ddots & \ddots & \ddots & \vdots \\ 0 & \vdots & \ddots & \ddots & \ddots & \vdots \\ 0 & \vdots & \ddots & \ddots & \ddots & \vdots \\ 0 & \vdots & \ddots & \ddots & \ddots & \ddots & \vdots \\ 0 & \vdots & \ddots & \ddots & \ddots & \ddots & \vdots \\ 0 & \vdots & \ddots & \ddots & \ddots & \ddots & \ddots \\ 0 & \vdots & \ddots & \ddots & \ddots & \ddots & \vdots \\ 0 & \vdots & \ddots & \ddots & \ddots & \ddots & \ddots & \vdots \\ 0 & \vdots & \ddots & \ddots & \ddots & \ddots & \ddots & \vdots \\ 0 & \vdots & \ddots & \ddots & \ddots & \ddots & \ddots & \ddots \\ 0 & \vdots & \ddots & \ddots & \ddots & \ddots & \ddots & \vdots \\ 0 & \vdots & \ddots \\ 0 & \vdots & \ddots & \ddots & \ddots & \ddots &$$

In addition, the boundary conditions are applied to the matrix \mathbf{A} and the vector \mathbf{b} to solve the system of equations. The boundary conditions are applied to the cells of \mathbf{b} and \mathbf{A} as follows:

- 1. For u(0, y) = 1:
 - Set $b_{(i-1)n+1} = 1$
 - Set $A_{(i-1)n+1,(i-1)n+1} = 1$
- 2. For u(1, y) = 1:
 - Set $b_{(i-1)n+n} = 1$

- Set $A_{(j-1)n+n,(j-1)n+n} = 1$
- 3. For v(0, y) = 0:
 - Set $b_{n^2+(j-1)n+1} = 0$
 - Set $A_{n^2+(j-1)n+1,n^2+(j-1)n+1} = 1$
- 4. For v(1, y) = 0:
 - Set $b_{n^2+(j-1)n+n} = 0$
 - Set $A_{n^2+(j-1)n+n,n^2+(j-1)n+n} = 1$
- 5. For $v(x, \infty) = 0$:
 - Set $b_{n^2+(n-1)n+i} = 0$
 - Set $A_{n^2+(n-1)n+i,n^2+(n-1)n+i} = 1$

Task 2.3:

$$\begin{split} & \text{import numpy as np} \\ & \text{import scipy.sparse.linalg as spla} \\ & \text{M2} = \text{spla.spilu}(A) \\ & \text{x} = \text{spla.gmres}(A,b,M=M2) \end{split}$$

HINT per chatty: come utilizzare gmres per risolvere le non linearita del problema, come specificato sopra.

References

- [1] CFD Repository,
 Available at: https://github.com/GiuseppePisante/CFD.git
- [2] GitHub Copilot, GitHub. Available at: https://github.com/features/copilot