

# Lab Notes

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# Chapter 1

## To Do

### 1.1 Coding

- Test split-WENO in 2D
- Implement in CUDA
- Solid EOSs
- Implement Barton's damage model
- Test compressible Euler vs GPR - use narrowing domain from Toro's book
- Try conservative formulation [Peshkov, Grmela, Romenski]

### 1.2 Theoretical

- Investigate approximate Riemann solvers (e.g. Dumbser's HLLEM)
- Convergence of conservation of mass in RGFM

### 1.3 Papers

- Isobaric cookoff (make cookoff the focus)
- Split solver vs ADER-WENO
- Application of ADER-WENO to Barton's solid model (with Tome)
- HPR-RGFM paper (solve stationarity of interface solver under some conditions)
- Application of ADER-WENO to equations in other areas of Physics, Biology, & Economics

## Chapter 2

# Faster Solvers

### 2.1 Improved Multidimensional WENO Oscillation Indicator

Given 2D reconstruction on stencil  $S_j$ :

$$w_j(x, y) = \tilde{w}_{pq} \psi_p(x) \psi_q(y) \quad (2.1)$$

the oscillation indicator for this reconstruction is [1]:

$$\begin{aligned} o_j &= \sum_{|\alpha|=1}^N \int_{C_i} (D^\alpha w_j)^2 d\mathbf{x} \\ &= \int_0^1 \left\{ \left( \frac{\partial w_j}{\partial x} \right)^2 + \left( \frac{\partial w_j}{\partial y} \right)^2 + \left( \frac{\partial^2 w_j}{\partial x^2} \right)^2 + \left( \frac{\partial^2 w_j}{\partial y^2} \right)^2 + \left( \frac{\partial^2 w_j}{\partial x \partial y} \right)^2 \right\} d\chi \\ &= \int_0^1 \left\{ \left( \tilde{w}_{pq} \psi'_p(x) \psi_q(y) \right)^2 + \left( \tilde{w}_{pq} \psi_p(x) \psi'_q(y) \right)^2 + \left( \tilde{w}_{pq} \psi''_p(x) \psi_q(y) \right)^2 + \left( \tilde{w}_{pq} \psi_p(x) \psi'_q(y) \right)^2 + \left( \tilde{w}_{pq} \psi'_p(x) \psi'_q(y) \right)^2 \right\} d\chi \\ &= \int_0^1 \left\{ \tilde{w}_{p_1 q_1} \psi'_{p_1}(x) \psi_{q_1}(y) \tilde{w}_{p_2 q_2} \psi'_{p_2}(x) \psi_{q_2}(y) + \dots \right\} d\chi \\ &= \tilde{w}_{p_1 q_1} \tilde{w}_{p_2 q_2} \int_{C_i} \left\{ \psi'_{p_1}(x) \psi_{q_1}(y) \psi'_{p_2}(x) \psi_{q_2}(y) + \psi_{p_1}(x) \psi_{q_1}(y) \psi_{p_2}(x) \psi_{q_2}(y) + \dots \right\} d\chi \\ &= \tilde{w}_{p_1 q_1} \tilde{w}_{p_2 q_2} \Sigma_{p_1 p_2 q_1 q_2} \end{aligned} \quad (2.2)$$

where

$$\Sigma = \Sigma^{(1)} \otimes \Sigma^{(0)} + \Sigma^{(0)} \otimes \Sigma^{(1)} + \Sigma^{(2)} \otimes \Sigma^{(0)} + \Sigma^{(0)} \otimes \Sigma^{(2)} + \Sigma^{(1)} \otimes \Sigma^{(1)} \quad (2.3)$$

$$\Sigma_{ij}^{(\beta)} = \int_0^1 \psi_i^{(\beta)} \psi_j^{(\beta)} dx \quad (2.4)$$

## 2.2 Fast WENO Oscillation Indicator Calculation

The WENO oscillation indicator is defined as:

$$o = \Sigma_{mn} w_m w_n \quad (2.5)$$

where  $w_i$  are the WENO coefficients calculated for a particular stencil, and:

$$\Sigma_{mn} = \sum_{\alpha=1}^N \int_0^1 \psi_m^{(\alpha)} \psi_n^{(\alpha)} \quad (2.6)$$

By considering that:

$$o = \sum_{\alpha=1}^N \int_0^1 \left( \frac{d^\alpha w}{dx^\alpha} \right)^2 > 0 \quad (2.7)$$

we have that  $\Sigma$  is symmetric positive definite. Thus, it has a Cholesky decomposition  $\Sigma = LL^T$ . Thus:

$$o = \|w^T L\|^2 \quad (2.8)$$

$L$  can be precalculated, and  $o$  calculated quickly as:

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```

1: o = 0
2: for j = 1...n do
3:   tmp = 0
4:   for i = j...n do
5:     tmp = tmp + w(i) * L(i,j)
6:   end for
7:   o = o + tmp * tmp
8: end for

```

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## 2.3 Approximating Interface Terms in FV

Instead of calculating the following:

$$\int D(q^-(x_0, t), q^+(x_0, t)) dt \quad (2.9)$$

I propose calculating the following:

$$D\left(\frac{1}{\Delta t} \int q^-(x_0, t) dt, \frac{1}{\Delta t} \int q^+(x_0, t) dt\right) \quad (2.10)$$

This obtains a large speedup with no discernable difference in the results of Stokes' First Problem.

## 2.4 Analytical Results for Basis Vectors

For  $N = 1$ , the Gauss-Legendre nodes on  $[0, 1]$  are  $\left\{ \frac{1}{2} \left( 1 - \frac{1}{\sqrt{3}} \right), \frac{1}{2} \left( 1 + \frac{1}{\sqrt{3}} \right) \right\}$ . Thus:

$$\psi_1(x) = -\sqrt{3}x + \frac{1 + \sqrt{3}}{2} \quad (2.11a)$$

$$\psi_2(x) = \sqrt{3}x + \frac{1 - \sqrt{3}}{2} \quad (2.11b)$$

$$\psi_1(1) = \frac{1 - \sqrt{3}}{2} \quad (2.12a)$$

$$\psi_2(1) = \frac{1 + \sqrt{3}}{2} \quad (2.12b)$$

$$\psi_1(1) \psi_1(1) = 1 - \frac{\sqrt{3}}{2} \quad (2.13a)$$

$$\psi_1(1) \psi_2(1) = -\frac{1}{2} \quad (2.13b)$$

$$\psi_2(1) \psi_2(1) = 1 + \frac{\sqrt{3}}{2} \quad (2.13c)$$

$$\int_m^{m+1} \psi_1(x) dx = \frac{-\sqrt{3}}{2} (2m+1) + \frac{1 + \sqrt{3}}{2} = \frac{1}{2} - m\sqrt{3} \quad (2.14a)$$

$$\int_m^{m+1} \psi_2(x) dx = \frac{\sqrt{3}}{2} (2m+1) + \frac{1 - \sqrt{3}}{2} = \frac{1}{2} + m\sqrt{3} \quad (2.14b)$$

The WENO matrices are:

$$\begin{pmatrix} \frac{1}{2} & \frac{1}{2} \\ \frac{1}{2} - \sqrt{3} & \frac{1}{2} + \sqrt{3} \end{pmatrix}, \begin{pmatrix} \frac{1}{2} + \sqrt{3} & \frac{1}{2} - \sqrt{3} \\ \frac{1}{2} & \frac{1}{2} \end{pmatrix} \quad (2.15)$$

The inverses are:

$$\frac{1}{\sqrt{3}} \begin{pmatrix} \sqrt{3} + \frac{1}{2} & -\frac{1}{2} \\ \sqrt{3} - \frac{1}{2} & \frac{1}{2} \end{pmatrix}, \frac{1}{\sqrt{3}} \begin{pmatrix} \frac{1}{2} & \sqrt{3} - \frac{1}{2} \\ -\frac{1}{2} & \sqrt{3} + \frac{1}{2} \end{pmatrix} \quad (2.16)$$

The weights for both nodes are 0.5 so  $\int_0^1 \psi_i \psi_j dx = \frac{\delta_{ij}}{2}$  and  $\int_0^1 \psi_i \psi_j' dx = (-1)^j \frac{\sqrt{3}}{2}$ .

$$\begin{aligned} I_{11} - I_2^T &= \frac{1}{2} \begin{pmatrix} 2 - \sqrt{3} & -1 \\ -1 & 2 + \sqrt{3} \end{pmatrix} - \frac{1}{2} \begin{pmatrix} -\sqrt{3} & -\sqrt{3} \\ \sqrt{3} & \sqrt{3} \end{pmatrix} \\ &= \frac{1}{2} \begin{pmatrix} 2 & -(1 - \sqrt{3}) \\ -(1 + \sqrt{3}) & 2 \end{pmatrix} \end{aligned} \quad (2.17)$$

$$(I_{11} - I_2^T)^{-1} = \frac{1}{3} \begin{pmatrix} 2 & 1 - \sqrt{3} \\ 1 + \sqrt{3} & 2 \end{pmatrix} \quad (2.18)$$

Using a precalculated, analytical form of  $U$  in the DG predictor for  $N = 1$  obtains a ~30% speedup on Stokes' First Problem.

## 2.5 Distortion ODEs

### 2.5.1 Linearized Distortion ODEs Solver

Note that  $A^* = \left(\frac{\rho}{\rho_0}\right)^{\frac{1}{3}} I$  is a stationary point of the ODE for  $A$ . Linearizing the ODE around  $A^*$  gives:

$$\begin{aligned} \frac{dA}{dt} &\approx J_A(A^*)(A - A^*) \\ &= \frac{-3}{\tau_1} \left(\frac{\rho}{\rho_0}\right)^{\frac{5}{3}} \left( \left(\frac{\rho}{\rho_0}\right)^{\frac{2}{3}} \delta_{in} \delta_{mj} + \left(\frac{\rho}{\rho_0}\right)^{\frac{2}{3}} \delta_{jn} \delta_{im} + \left(\frac{\rho}{\rho_0}\right)^{\frac{2}{3}} \delta_{im} \delta_{jn} - \frac{1}{3} \left(\frac{\rho}{\rho_0}\right)^{\frac{2}{3}} \delta_{im} \delta_{jn} \delta_{kl} \delta_{kl} - \frac{2}{3} \left(\frac{\rho}{\rho_0}\right)^{\frac{2}{3}} \delta_{ij} \delta_{mn} \right) \\ &\quad \times \left( A_{mn} - \left(\frac{\rho}{\rho_0}\right)^{\frac{1}{3}} \delta_{mn} \right) \\ &= \frac{-3}{\tau_1} \left(\frac{\rho}{\rho_0}\right)^{\frac{7}{3}} \left( \delta_{in} \delta_{mj} + \delta_{im} \delta_{jn} - \frac{2}{3} \delta_{ij} \delta_{mn} \right) \left( A_{mn} - \left(\frac{\rho}{\rho_0}\right)^{\frac{1}{3}} \delta_{mn} \right) \\ &= \frac{-3}{\tau_1} \left(\frac{\rho}{\rho_0}\right)^{\frac{7}{3}} \left( A_{mn} \left( \delta_{in} \delta_{mj} + \delta_{im} \delta_{jn} - \frac{2}{3} \delta_{ij} \delta_{mn} \right) - \left(\frac{\rho}{\rho_0}\right)^{\frac{1}{3}} \delta_{mn} \left( \delta_{in} \delta_{mj} + \delta_{im} \delta_{jn} - \frac{2}{3} \delta_{ij} \delta_{mn} \right) \right) \\ &= \frac{-3}{\tau_1} \left(\frac{\rho}{\rho_0}\right)^{\frac{7}{3}} \left( \left( A_{ji} + A_{ij} - \frac{2}{3} \text{tr}(A) \delta_{ij} \right) - \left(\frac{\rho}{\rho_0}\right)^{\frac{1}{3}} (\delta_{ij} + \delta_{ij} - 2\delta_{ij}) \right) \\ &= \frac{-3}{\tau_1} \left(\frac{\rho}{\rho_0}\right)^{\frac{7}{3}} \left( A + A^T - \frac{2}{3} \text{tr}(A) I \right) \end{aligned} \quad (2.19)$$

The matrix for this system, in row-major form, is:

$$\frac{-3}{\tau_1} \left(\frac{\rho}{\rho_0}\right)^{\frac{7}{3}} \begin{pmatrix} \frac{4}{3} & 0 & 0 & 0 & -\frac{2}{3} & 0 & 0 & 0 & -\frac{2}{3} \\ 0 & 1 & 0 & 1 & 0 & 0 & 0 & 0 & 0 \\ 0 & 0 & 1 & 0 & 0 & 0 & 1 & 0 & 0 \\ 0 & 1 & 0 & 1 & 0 & 0 & 0 & 0 & 0 \\ -\frac{2}{3} & 0 & 0 & 0 & \frac{4}{3} & 0 & 0 & 0 & -\frac{2}{3} \\ 0 & 0 & 0 & 0 & 0 & 1 & 0 & 1 & 0 \\ 0 & 0 & 1 & 0 & 0 & 0 & 1 & 0 & 0 \\ 0 & 0 & 0 & 0 & 0 & 1 & 0 & 1 & 0 \\ -\frac{2}{3} & 0 & 0 & 0 & -\frac{2}{3} & 0 & 0 & 0 & \frac{4}{3} \end{pmatrix} \quad (2.20)$$

The eigenvalues and eigenvectors are:

$$\{0, 0, 0, 0, -2k, -2k, -2k, -2k, -2k\} \quad (2.21)$$

$$\begin{pmatrix} 0 \\ 1 \\ 0 \\ -1 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \end{pmatrix}
\begin{pmatrix} 0 \\ 0 \\ 1 \\ 0 \\ 0 \\ -1 \\ 0 \\ 0 \\ 0 \end{pmatrix}
\begin{pmatrix} 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 1 \\ -1 \\ 0 \\ 0 \end{pmatrix}
\begin{pmatrix} 1 \\ 0 \\ 0 \\ 0 \\ 1 \\ 0 \\ 0 \\ 0 \\ 1 \end{pmatrix}
\begin{pmatrix} -1 \\ 0 \\ 0 \\ 0 \\ 1 \\ 0 \\ 0 \\ 0 \\ 0 \end{pmatrix}
\begin{pmatrix} -1 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 1 \\ 0 \end{pmatrix}
\begin{pmatrix} 0 \\ 1 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \end{pmatrix}
\begin{pmatrix} 0 \\ 0 \\ 1 \\ 0 \\ 0 \\ 1 \\ 0 \\ 0 \\ 0 \end{pmatrix}
\begin{pmatrix} 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 1 \\ 0 \\ 1 \\ 0 \end{pmatrix}
\quad (2.22)$$

where  $k = \frac{3}{\tau_1} \left( \frac{\rho}{\rho_0} \right)^{\frac{7}{3}}$ . Thus, the solution is:

$$\begin{aligned}
& \frac{A_{12} - A_{21}}{2} \begin{pmatrix} 0 & 1 & 0 \\ -1 & 0 & 0 \\ 0 & 0 & 0 \end{pmatrix} + \frac{A_{13} - A_{31}}{2} \begin{pmatrix} 0 & 0 & 1 \\ 0 & 0 & 0 \\ -1 & 0 & 0 \end{pmatrix} + \frac{A_{23} - A_{32}}{2} \begin{pmatrix} 0 & 0 & 0 \\ 0 & 0 & 1 \\ 0 & -1 & 0 \end{pmatrix} \\
& + \frac{A_{11} + A_{22} + A_{33}}{3} \begin{pmatrix} 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 1 \end{pmatrix} \\
& + \frac{2A_{22} - A_{11} - A_{33}}{3} e^{-2kt} \begin{pmatrix} -1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 0 \end{pmatrix} + \frac{2A_{33} - A_{11} - A_{22}}{3} e^{-2kt} \begin{pmatrix} -1 & 0 & 0 \\ 0 & 0 & 0 \\ 0 & 0 & 1 \end{pmatrix} \\
& + \frac{A_{12} + A_{21}}{2} e^{-2kt} \begin{pmatrix} 0 & 1 & 0 \\ 1 & 0 & 0 \\ 0 & 0 & 0 \end{pmatrix} + \frac{A_{13} + A_{31}}{2} e^{-2kt} \begin{pmatrix} 0 & 0 & 1 \\ 0 & 0 & 0 \\ 1 & 0 & 0 \end{pmatrix} + \frac{A_{23} + A_{32}}{2} e^{-2kt} \begin{pmatrix} 0 & 0 & 0 \\ 0 & 0 & 1 \\ 0 & 1 & 0 \end{pmatrix}
\end{aligned} \quad (2.23)$$

This is equal to:

$$\frac{1}{2} (A - A^T) + \frac{\text{tr}(A)}{3} I + e^{-2kt} \left( \frac{1}{2} (A + A^T) - \frac{\text{tr}(A)}{3} I \right) \quad (2.24)$$

Results with Stokes' First Problem look good with this linearisation. The ODE step takes a negligible amount of time, meaning that if accuracy is maintained to second order, the solver is now fast enough.

### 2.5.2 Linearized Reduced Distortion ODE Solver

Taking system (??), note that the Jacobian of the system is given by:

$$J = -k \begin{pmatrix} 4x_1 - x_2 - x_3 & -x_1 & -x_1 \\ -x_2 & 4x_2 - x_3 - x_1 & -x_3 \\ -x_3 & -x_3 & 4x_3 - x_1 - x_2 \end{pmatrix} \quad (2.25)$$

Evaluated at stationary point  $x_i = \sqrt[3]{c}$  we have:

$$J(\mathbf{x}_0) = -k \sqrt[3]{c} \begin{pmatrix} 2 & -1 & -1 \\ -1 & 2 & -1 \\ -1 & -1 & 2 \end{pmatrix} \quad (2.26)$$



Thus, the system is linearized to:

$$\begin{aligned} \frac{d\mathbf{x}}{dt} &\approx -k\sqrt[3]{c} \begin{pmatrix} 2 & -1 & -1 \\ -1 & 2 & -1 \\ -1 & -1 & 2 \end{pmatrix} \left( \begin{pmatrix} x_1 \\ x_2 \\ x_3 \end{pmatrix} - \sqrt[3]{c} \begin{pmatrix} 1 \\ 1 \\ 1 \end{pmatrix} \right) \\ &= k\sqrt[3]{c} \begin{pmatrix} -2 & 1 & 1 \\ 1 & -2 & 1 \\ 1 & 1 & -2 \end{pmatrix} \begin{pmatrix} x_1 \\ x_2 \\ x_3 \end{pmatrix} \end{aligned} \quad (2.27)$$

The eigenvalues of this system matrix are  $\{-3k\sqrt[3]{c}, -3k\sqrt[3]{c}, 0\}$  and the eigenvectors are:

$$\begin{pmatrix} -1 \\ 0 \\ 1 \end{pmatrix}, \begin{pmatrix} 0 \\ -1 \\ 1 \end{pmatrix}, \begin{pmatrix} 1 \\ 1 \\ 1 \end{pmatrix} \quad (2.28)$$

Thus, the linearized solution is:

$$\mathbf{x}(t) = \frac{-2x_1 + x_2 + x_3}{3} e^{-3k\sqrt[3]{c}t} \begin{pmatrix} -1 \\ 0 \\ 1 \end{pmatrix} + \frac{x_1 - 2x_2 + x_3}{3} e^{-3k\sqrt[3]{c}t} \begin{pmatrix} 0 \\ -1 \\ 1 \end{pmatrix} + \frac{x_1 + x_2 + x_3}{3} \begin{pmatrix} 1 \\ 1 \\ 1 \end{pmatrix} \quad (2.29)$$

This may represent a faster way to calculate the evolution of the stretch terms of  $A$ . Note that some kind of normalization will probably be necessary, as:

$$\frac{x_1 + x_2 + x_3}{3} \geq (x_1 x_2 x_3)^{\frac{1}{3}} \quad (2.30)$$

with equality if and only if  $x_1 = x_2 = x_3$ .

## 2.6 Primitive WENO and DG Reconstruction

As suggested in [2], the WENO and DG can be performed in primitive variables, which is less computationally expensive than evaluating fluxes using conserved variables. Achieves around 20% speedup in DG step, at double cost in WENO step. Minimal speedup in FV step, as both primitive and conserved variables must be calculated for the flux updates. Not enough.

## 2.7 Change to Row-Major Ordering

The original GPR papers state the equations for  $A$  in column-major order, probably because the authors use Fortran. For C++ and Python implementations it is faster to work in row-major order. ~10% speedup was achieved by implementing this.

The GPR equations are:

$$\frac{\partial \rho}{\partial t} + \frac{\partial (\rho v_k)}{\partial x_k} = 0 \quad (2.31a)$$

$$\frac{\partial (\rho E)}{\partial t} + \frac{\partial (\rho E v_k + (p \delta_{ik} - \sigma_{ik}) v_i + q_k)}{\partial x_k} = 0 \quad (2.31b)$$

$$\frac{\partial (\rho v_i)}{\partial t} + \frac{\partial (\rho v_i v_k + p \delta_{ik} - \sigma_{ik})}{\partial x_k} = 0 \quad (2.31c)$$

$$\frac{\partial A_{ij}}{\partial t} + \frac{\partial (A_{ik} v_k)}{\partial x_j} + v_k \left( \frac{\partial A_{ij}}{\partial x_k} - \frac{\partial A_{ik}}{\partial x_j} \right) = -\frac{\psi_{ij}}{\theta_1(\tau_1)} \quad (2.31d)$$

$$\frac{\partial (\rho J_i)}{\partial t} + \frac{\partial (\rho J_i v_k + T \delta_{ik})}{\partial x_k} = -\frac{\rho H_i}{\theta_2(\tau_2)} \quad (2.31e)$$

Under row-major ordering, we have:

$$\mathbf{Q} = \left( \begin{array}{cccccccccccccccccccc} \rho & \rho E & \rho v_1 & \rho v_2 & \rho v_3 & A_{11} & A_{12} & A_{13} & A_{21} & A_{22} & A_{23} & A_{31} & A_{32} & A_{33} & \rho J_1 & \rho J_2 & \rho J_3 \end{array} \right)^T \quad (2.32a)$$

$$\mathbf{P} = \left( \begin{array}{cccccccccccccccccccc} \rho & p & v_1 & v_2 & v_3 & A_{11} & A_{21} & A_{31} & A_{12} & A_{22} & A_{32} & A_{13} & A_{23} & A_{33} & J_1 & J_2 & J_3 \end{array} \right)^T \quad (2.32b)$$

$$\mathbf{F}_1 = \left( \begin{array}{c} \rho v_1 \\ \rho v_1 E + v_1 p - \sigma_{1m} v_m + q_1 \\ \rho v_1^2 + p - \sigma_{11} \\ \rho v_1 v_2 - \sigma_{12} \\ \rho v_1 v_3 - \sigma_{13} \\ A_{1m} v_m \\ 0 \\ 0 \\ 0 \\ A_{2m} v_m \\ 0 \\ 0 \\ 0 \\ A_{3m} v_m \\ 0 \\ 0 \\ 0 \\ \rho J_1 v_1 + T \\ \rho J_2 v_1 \\ \rho J_3 v_1 \end{array} \right) \quad \mathbf{F}_2 = \left( \begin{array}{c} \rho v_2 \\ \rho v_2 E + v_2 p - \sigma_{2m} v_m + q_2 \\ \rho v_1 v_2 - \sigma_{21} \\ \rho v_2^2 + p - \sigma_{22} \\ \rho v_2 v_3 - \sigma_{23} \\ 0 \\ A_{1m} v_m \\ 0 \\ 0 \\ A_{2m} v_m \\ 0 \\ 0 \\ 0 \\ A_{3m} v_m \\ 0 \\ 0 \\ 0 \\ \rho J_1 v_2 \\ \rho J_2 v_2 + T \\ \rho J_3 v_2 \end{array} \right) \quad \mathbf{F}_3 = \left( \begin{array}{c} \rho v_3 \\ \rho v_3 E + v_3 p - \sigma_{3m} v_m + q_3 \\ \rho v_1 v_3 - \sigma_{31} \\ \rho v_2 v_3 - \sigma_{32} \\ \rho v_3^2 + p - \sigma_{33} \\ 0 \\ 0 \\ 0 \\ A_{1m} v_m \\ 0 \\ 0 \\ 0 \\ A_{2m} v_m \\ 0 \\ 0 \\ 0 \\ A_{3m} v_m \\ \rho J_1 v_3 \\ \rho J_2 v_3 \\ \rho J_3 v_3 + T \end{array} \right) \quad (2.33)$$

[illegible]

$$\mathbf{S} = -\frac{1}{\theta_1(\tau_1)} \begin{pmatrix} 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ \psi_{11} \\ \psi_{12} \\ \psi_{13} \\ \psi_{21} \\ \psi_{22} \\ \psi_{23} \\ \psi_{31} \\ \psi_{32} \\ \psi_{33} \\ 0 \\ 0 \\ 0 \end{pmatrix} - \frac{1}{\theta_2(\tau_2)} \begin{pmatrix} 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ \rho H_1 \\ \rho H_2 \\ \rho H_3 \end{pmatrix} \quad (2.37)$$

$$\Psi_{ij} = \rho v_i v_j - \sigma_{ij} \quad (2.38a)$$

$$\Phi_{ij}^k = \rho v_k \psi_{ij} - v_m \frac{\partial \sigma_{mk}}{\partial A_{ij}} \quad (2.38b)$$

$$\Omega_i = v_i (E + \rho E_\rho) - \frac{\sigma_{im} v_m}{\rho} + T_\rho H_i \quad (2.38c)$$

$$\Upsilon = \frac{\|\mathbf{v}\|^2 + \mathbf{H} \cdot \mathbf{J} - E - \rho E_\rho}{\rho E_p} \quad (2.38d)$$

$$\tilde{\mathbf{H}} = E_{\mathbf{J}\mathbf{J}} \quad (2.38e)$$

$$\mathbf{S}_p = \frac{1}{\theta_1(\tau_1)} \begin{pmatrix} 0 \\ (\gamma - 1) \rho \|\psi\|_F^2 \\ 0 \\ 0 \\ 0 \\ -\psi_{11} \\ -\psi_{12} \\ -\psi_{13} \\ -\psi_{21} \\ -\psi_{22} \\ -\psi_{23} \\ -\psi_{31} \\ -\psi_{32} \\ -\psi_{33} \\ 0 \\ 0 \\ 0 \end{pmatrix} + \frac{1}{\theta_2(\tau_2)} \begin{pmatrix} 0 \\ (\gamma - 1) \rho \|\mathbf{H}\|^2 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ 0 \\ -H_1 \\ -H_2 \\ -H_3 \end{pmatrix} \quad (2.47)$$

[illegible]

[illegible]



[illegible]











## Chapter 3

# Slow Flow

### 3.1 Studying numerical smearing with slow flow past a barrier

A checkerboard pattern appears around the corner of the barrier, leading to a crash, using reflective boundary conditions (in velocity) for the barrier. Do we need a staggered grid?

## Chapter 4

# RGFM

The RGFM does nothing without a temperature fix when applied to the heat conduction test. The linearisation upon which it is based results in a stationary solution when  $q_L = q_R$  and  $\sigma_L = \sigma_R$  initially. Barton's RGFM is similar. Should  $q$  be fixed? Maybe use analytical solution to heat equation at  $t = \Delta t$ ?

# Bibliography

- [1] Doron Levy. A Third Order Central WENO Scheme for 2D Conservation Laws 1 Introduction 2 Description of the scheme. 33:415–421, 1998.
- [2] Olindo Zanotti and Michael Dumbser. Efficient conservative ADER schemes based on WENO reconstruction and space-time predictor in primitive variables. *Computational Astrophysics and Cosmology*, 3(1):1, 2016.