

Computer project 2.2

Wednesday, November 23, 2022

9:06 AM

(2) Temporally, discretize Eq. (9) using Crank-Nicolson scheme with a time step size of Δt . At the j th time step, the solution is denoted by $\mathbf{u}_j = \mathbf{u}(j\Delta t)$, $j = 0, 1, \dots, N_t$, where $N_t = \frac{T}{\Delta t}$.
Show that

$$\mathbf{T}\mathbf{u}_{n+1} = \mathbf{S}\mathbf{u}_n + \mathbf{f} \quad (17)$$

where the initial condition is $\mathbf{u}_0 = \mathbf{0}$ as given by Eq. (1), $\mathbf{f} = \Delta t \tilde{\mathbf{f}}$, and

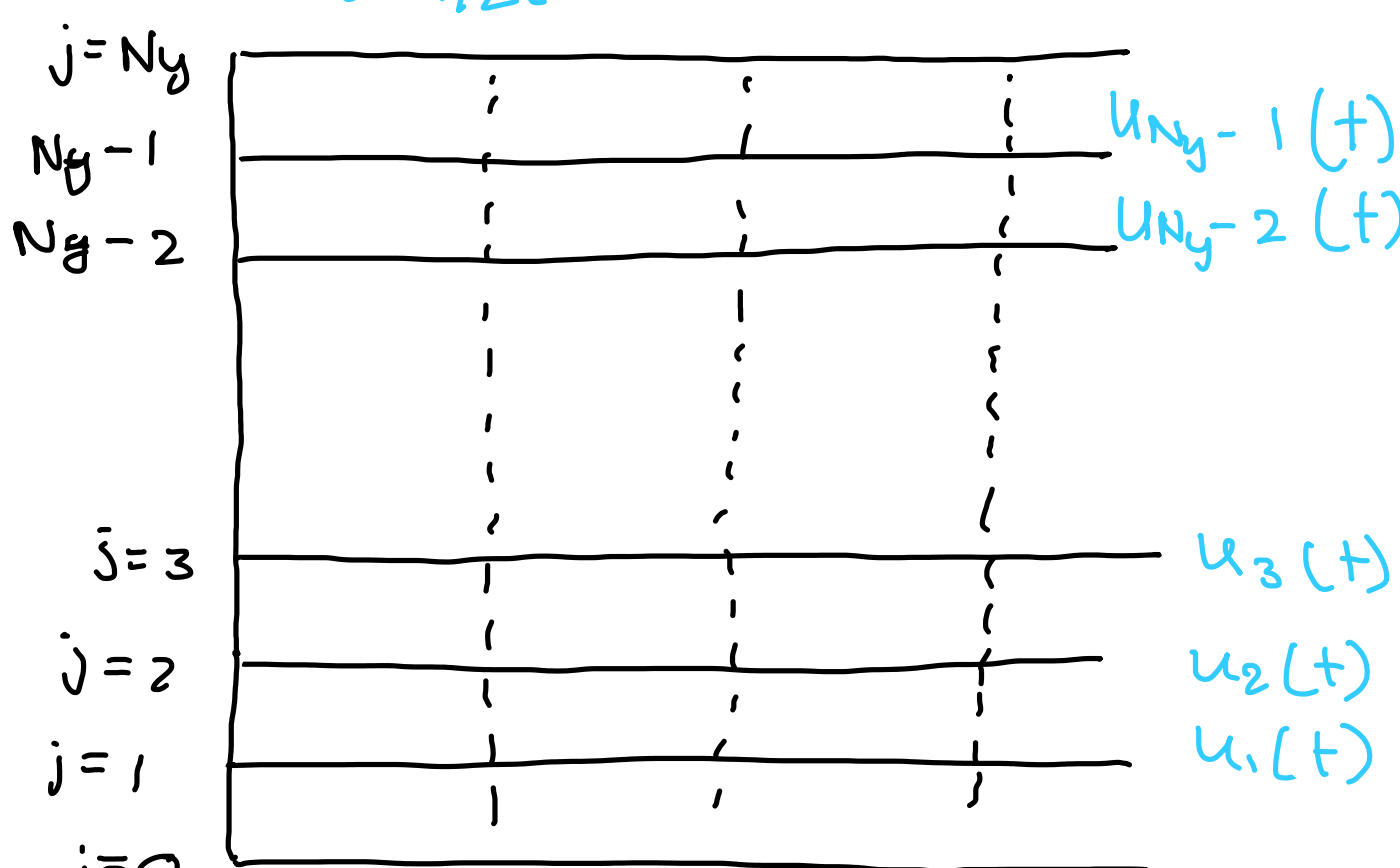
$$\mathbf{T} = \mathbf{I} - \frac{\Delta t}{2} \mathbf{A}, \quad \mathbf{S} = \mathbf{I} + \frac{\Delta t}{2} \mathbf{A} \quad (18)$$

$$\text{eq. (9)} \Rightarrow \dot{\mathbf{u}} = \mathbf{A}\mathbf{u} + \tilde{\mathbf{f}}$$

$$\text{Step size } \Delta t \quad u_j = u(j\Delta t), \quad j = 0, 1, \dots, N_t, \text{ where } N_t = \frac{T}{\Delta t}$$

$$\frac{\partial u}{\partial t} = \mathbf{A}u + \tilde{\mathbf{f}} \quad r = K / \Delta t^2$$

$$N_y = H / \Delta y \quad \text{let } \tau = H$$



$$y = 2\Delta y$$

$$u_t = K u_{yy}$$

$$u_2' = K / \Delta y^2 (u_1(t) - 2u_2(t) + u_3(t))$$

$$u_3' = K / \Delta y^2 (u_2(t) - 2u_3(t) + u_y(t))$$

LU decomp. of A

$$\frac{d}{dt} \begin{bmatrix} u_{N_y-1} \\ u_{N_y-2} \\ \vdots \\ u_3 \\ u_2 \\ u_1 \end{bmatrix} = \frac{K}{\Delta y^2} \begin{bmatrix} A_{3-2} & A_{q+1} & & & & \\ & 1 & -2 & 1 & & \\ & & \ddots & \ddots & \ddots & \\ & & & 1 & -2 & 1 \\ & & & & A_{2+1} & A_{i-2} \end{bmatrix} \begin{bmatrix} u_{N_y-1} \\ u_{N_y-2} \\ \vdots \\ u_3 \\ u_2 \\ u_1 \end{bmatrix} + \begin{bmatrix} \tilde{f}_2 \\ 0 \\ 0 \\ \vdots \\ 0 \\ 0 \\ \tilde{f}_1 \end{bmatrix}$$

Top corner of \underline{A} : u_0, u_1, u_2

+ Bottom

$$A_3 = A_1 \quad A_4 = A_2$$

Solve u_1, u_2

$$u_y(0, t) = \frac{-3u_0(t) + 4u_1(t) - u_2(t)}{2\Delta y} = -Q_1 \leftrightarrow$$

Solve for u_0

$$-3u_0 = -Q_1 2\Delta y - 4u_1 + u_2 \rightarrow u_0 = -Q_1 2\Delta y + \frac{4}{3}u_1 - \frac{1}{3}u_2$$

$$u_0 = \frac{4}{3}u_1 - \frac{1}{3}u_2 - Q_1 2\Delta y$$

$$A_1$$

$$A_2$$

$$A_{i-2} = -2/3 = A_3 = -2$$

$$A_{2+1} = 2/3 = A_4 + 1$$

$$u_1' = \frac{K}{\Delta y^2} (u_0(t) - 2u_1(t) + u_2(t))$$

$$u_0(t) = \frac{2}{3}\Delta y Q_1 + \frac{4}{3}u_1(t) - \frac{1}{3}u_2(t)$$

top part N_y-2, N_y-1, N_y

solve for u_{N_y}

$u_1 \rightsquigarrow$ last term in front of a 0

then use $u_y(H, t)$

$$-Q_2 = \frac{u_{N_y-2} - 4u_{N_y-1} + 3u_{N_y}}{2\Delta y}$$

$$\frac{-2\Delta y Q_2}{3} + \frac{4u_{N_y-1}}{3} - \frac{u_{N_y-2}}{3} = u_{N_y}$$

$$\tilde{\mathbf{f}} \rightarrow Q_1 \rightarrow -Q_2$$

$$u_y(H, t) = \frac{u_{N_y-2}(t) - 4u_{N_y-1}(t) + 3u_{N_y}(t)}{2\Delta y} = -Q_2$$

$$\tilde{f}_1 \rightarrow \frac{2}{3}\Delta y (-Q_1) \leftarrow [u_1(t)]$$

$$\tilde{\mathbf{f}} = \frac{2K}{3\Delta y} \begin{bmatrix} Q_1 \\ \vdots \\ 0 \\ -Q_2 \end{bmatrix} \quad \leftarrow \text{common multiple in front of } Q_1 \text{ + } -Q_2 \text{ in } \tilde{\mathbf{f}} \text{ vector}$$

$$\frac{d}{dt} \begin{bmatrix} u_1 \\ u_2 \\ \vdots \\ u_{N_y-2} \\ u_{N_y-1} \end{bmatrix} = \frac{K}{\Delta y^2} \begin{bmatrix} -2/3 & 2/3 & & & \\ & 1 & -2 & 1 & \\ & & \ddots & \ddots & \ddots \\ & & & 1 & -2 & 1 \\ & & & & 2/3 & -2/3 \end{bmatrix} \begin{bmatrix} u_1 \\ u_2 \\ \vdots \\ u_{N_y-2} \\ u_{N_y-1} \end{bmatrix} + \frac{2K}{3\Delta y} \begin{bmatrix} Q_1 \\ 0 \\ \vdots \\ 0 \\ -Q_2 \end{bmatrix}$$

Proof of $\mathbf{T}\mathbf{u}_{k+1} = \mathbf{S}\mathbf{u}_k + \mathbf{f}$

For crank Nicolson: $k+1/2$

$$\begin{array}{c} | \quad | \quad | \\ k \quad k+1/2 \quad k+1 \end{array}$$

$$\dot{\mathbf{u}}_{k+1/2} = \mathbf{A}\mathbf{u}_{k+1/2} + \mathbf{f}$$

$$\dot{\mathbf{u}}_{k+1/2} = \frac{\mathbf{u}_{k+1} - \mathbf{u}_k}{\Delta t} \quad \mathbf{u}_{k+1/2} = \frac{1}{2}(\mathbf{u}_{k+1} + \mathbf{u}_k)$$

$$\frac{\mathbf{u}_{k+1} - \mathbf{u}_k}{\Delta t} = \mathbf{A} \left[\frac{1}{2}(\mathbf{u}_{k+1} + \mathbf{u}_k) \right] + \tilde{\mathbf{f}}$$

$$\mathbf{I}\mathbf{u}_{k+1} - \mathbf{I}\mathbf{u}_k = \frac{\Delta t}{2} \mathbf{A}\mathbf{u}_{k+1} + \frac{\Delta t}{2} \mathbf{A}\mathbf{u}_k + \tilde{\mathbf{f}} \cdot \Delta t$$

$$\rightarrow$$

$$= \underbrace{\left(\mathbf{I} - \frac{\Delta t}{2} \mathbf{A} \right)}_{\mathbf{T}} \mathbf{u}_{k+1} = \underbrace{\left(\mathbf{I} + \frac{\Delta t}{2} \mathbf{A} \right)}_{\mathbf{S}} \mathbf{u}_k + \underbrace{\tilde{\mathbf{f}} \Delta t}_{\mathbf{f}}$$

\rightarrow

$$\mathbf{T}\mathbf{u}_{k+1} = \mathbf{S}\mathbf{u}_k + \mathbf{f}$$

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