

1 **POINT SPREAD FUNCTION APPROXIMATION OF HIGH RANK**
2 **HESSIANS WITH LOCALLY SUPPORTED NON-NEGATIVE**
3 **INTEGRAL KERNELS***

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5 **Abstract.** We present an efficient matrix-free point spread function (PSF) method for approximating operators that have locally supported non-negative integral kernels. The PSF-based method
6 computes impulse responses of the operator at scattered points, and interpolates these impulse re-
7 sponses to approximate entries of the integral kernel. To compute impulse responses efficiently, we
8 apply the operator to Dirac combs associated with batches of point sources, which are chosen by
9 solving an ellipsoid packing problem. The ability to rapidly evaluate kernel entries allows us to con-
10 struct a hierarchical matrix (H-matrix) approximation of the operator. Further matrix computations
11 are then performed with fast H-matrix methods. This end-to-end procedure is illustrated on a blur
12 problem. We demonstrate the PSF-based method's effectiveness by using it to build preconditioners
13 for the Hessian operator arising in two inverse problems governed by partial differential equations
14 (PDEs): inversion for the basal friction coefficient in an ice sheet flow problem and for the initial
15 condition in an advective-diffusive transport problem. While for many ill-posed inverse problems the
16 Hessian of the data misfit term exhibits a low rank structure, and hence a low rank approximation
17 is suitable, for many problems of practical interest the numerical rank of the Hessian is still large.
18 The Hessian impulse responses on the other hand typically become more local as the numerical rank
19 increases, which benefits the PSF-based method. Numerical results reveal that the preconditioner
20 clusters the spectrum of the preconditioned Hessian near one, yielding roughly $5 \times 10 \times$ reductions
21 in the required number of PDE solves, as compared to classical regularization-based preconditioning
22 and no preconditioning. We also present a comprehensive numerical study for the influence of various
23 parameters (that control the shape of the impulse responses and the rank of the Hessian) on the
24 effectiveness of the advection-diffusion Hessian approximation. The results show that the PSF-based
25 method is able to form good approximations of high-rank Hessians using only a small number of
26 operator applications.
27

28 **Key words.** data scalability, Hessian, hierarchical matrix, high-rank, impulse response, local
29 translation invariance, matrix-free, moment methods, operator approximation, PDE constrained
30 inverse problems, point spread function, preconditioning, product convolution

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32 65N21, 86A22, 86A40

33 **1. Introduction.** We present an efficient *matrix-free* point spread function (PSF)
34 method for approximating operators $\mathcal{A} : L^2(\Omega) \rightarrow L^2(\Omega)'$ that have locally supported
35 non-negative integral kernels. Here, $\Omega \subset \mathbb{R}^d$ is a bounded domain, and $L^2(\Omega)'$ is
36 the space of real-valued continuous linear functionals on $L^2(\Omega)$. By “non-negative
37 integral kernel,” we mean that entries of \mathcal{A} 's integral kernel are non-negative num-
38 bers; this is not the same as positive semi-definiteness of \mathcal{A} . Such operators appear,
39 for instance, as Hessians in optimization and inverse problems governed by partial
40 differential equations (PDEs) [14, 20, 47], Schur complements in Schur complement
41 methods for solving partial differential equations and Poincare-Steklov operators in

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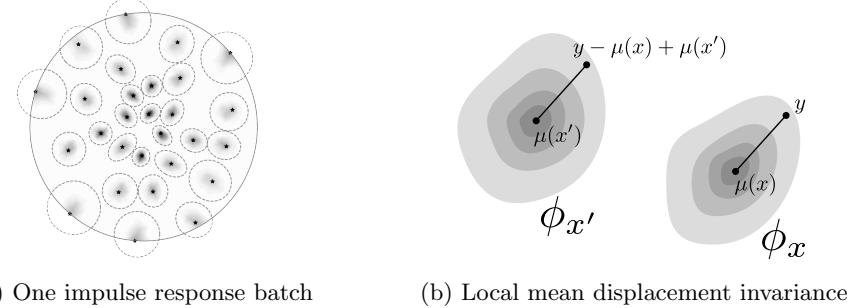


Fig. 1: (1a) One batch, η_b , of normalized impulse responses, ϕ_x , that arise from applying \mathcal{A} to a weighted sum of scattered point sources (see Section 5.2). Here, \mathcal{A} is the ice sheet inverse problem data misfit Gauss-Newton Hessian described in Section 7. Black stars are point source locations. Shading shows the magnitude of the normalized impulse responses (darker means larger function values). Dashed gray ellipses are estimated impulse response support ellipsoids based on the moment method in Section 4.1. The large circle is $\partial\Omega$. (1b) Illustration of impulse responses, ϕ_x and $\phi_{x'}$, corresponding to points x and x' . The operator \mathcal{A} is locally mean displacement invariant (Section 4.2) if $\phi_x(y) \approx \phi_{x'}(y - \mu(x) + \mu(x'))$ when x is close to x' . Here, $\mu(z)$ denotes the mean (center of mass) of ϕ_z .

42 domain decomposition methods (e.g., Dirichlet-to-Neumann maps) [16, 67, 73], co-
 43 variance operators in spatial statistics [17, 36, 37, 56], and blurring operators in imaging
 44 [22, 60]. Here, “matrix-free” means that we may apply \mathcal{A} and its transpose¹, \mathcal{A}^T ,
 45 to functions,

46 (1.1)
$$u \mapsto \mathcal{A}u \quad \text{and} \quad w \mapsto \mathcal{A}^T w,$$

47 via a black box computational procedure, but cannot easily access entries of \mathcal{A} ’s
 48 integral kernel. Evaluating the maps in (1.1) may require solving a subproblem that
 49 involves PDEs, or performing other costly computations.

50 The idea of the proposed method, which we refer to throughout the paper as
 51 the “PSF-based method,” is to use *impulse response interpolation* to form a high
 52 rank approximation of \mathcal{A} using a small number of operator applications. The impulse
 53 response, ϕ_x , associated with a point, x , is the Riesz representation² of the linear func-
 54 tional that results from applying \mathcal{A} to a delta distribution (i.e., point source, impulse)
 55 centered at x . We compute batches of impulse responses by applying \mathcal{A} to weighted
 56 sums of delta distributions associated with batches of points scattered throughout the
 57 domain (see Figure 1a). Batches of impulse responses may be thought of intuitively
 58 as sets of “columns” of the kernel (Figure 2). To choose the batches, we form ellipsoid
 59 estimates for the supports of all ϕ_x via a moment method (Figure 3) that involves
 60 applying \mathcal{A}^T to a small number of polynomials (see Section 4.1). We then use a greedy

¹Recall that $\mathcal{A}^T : L^2(\Omega) \rightarrow L^2(\Omega)'$ is the unique operator satisfying $(\mathcal{A}u)(w) = (\mathcal{A}^Tw)(u)$ for all $u, w \in L^2(\Omega)$, where $\mathcal{A}u \in L^2(\Omega)'$ is the result of applying \mathcal{A} to $u \in L^2(\Omega)$, and $(\mathcal{A}u)(w)$ is the result of applying that linear functional to $w \in L^2(\Omega)$, and similar for operations with \mathcal{A}^T .

²Recall that the Riesz representative of a functional $\rho \in L^2(\Omega)'$ with respect to the L^2 inner product is the unique function $\rho^* \in L^2(\Omega)$ such that $\rho(w) = (\rho^*, w)_{L^2(\Omega)}$ for all $w \in L^2(\Omega)$.

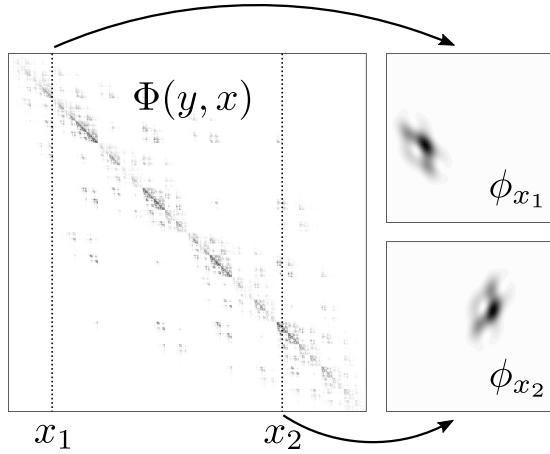


Fig. 2: Left: Matrix created by evaluating the integral kernel Φ for \mathcal{A} (Equation 3.1) at all pairs of mesh vertices. This illustration is for the integral kernel in Equation 7.4. Dark colors indicate large entries and light colors indicate small entries. Rows and columns are ordered according to a kd-tree hierarchical clustering. Right: Impulse responses associated with points $x_1, x_2 \in \Omega$, shown by the two dotted vertical lines. Intuitively, one may think of impulse responses as “columns” of the integral kernel.

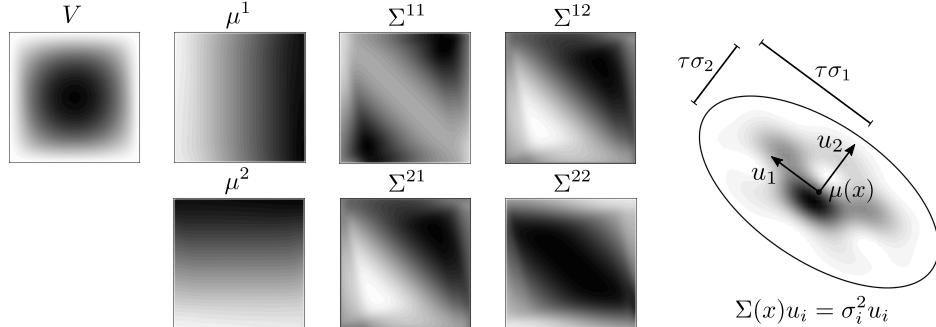


Fig. 3: Left: Impulse response moments. Scaling factor (V), mean (μ), and covariance (Σ). For each point $x \in \Omega$, the quantity $V(x)$ is the integral of ϕ_x over Ω , $\mu(x)$ is the location that ϕ_x is centered at, and $\Sigma(x)$ is a matrix with eigenvectors and eigenvalues that characterize the width of the support of ϕ_x about $\mu(x)$ (see Section 4.1). Right: Ellipsoid support for an impulse response. This ellipsoid is the set of points within τ standard deviations of the mean of the Gaussian distribution with mean $\mu(x)$ and covariance $\Sigma(x)$. The scaling factor $V(x)$ characterizes the magnitude of ϕ_x .

61 ellipsoid packing algorithm (Figure 4) to maximize the number of impulse responses
 62 per batch. Then we interpolate translated and scaled versions of these impulse re-
 63 sponses to approximate entries of the operator’s integral kernel (Figure 5). Adding
 64 more batches yields impulse responses at more points, increasing the approximation
 65 accuracy at the cost of one operator application per batch (Figure 6).

66 The PSF-based method we propose is loosely based on “product convolution”

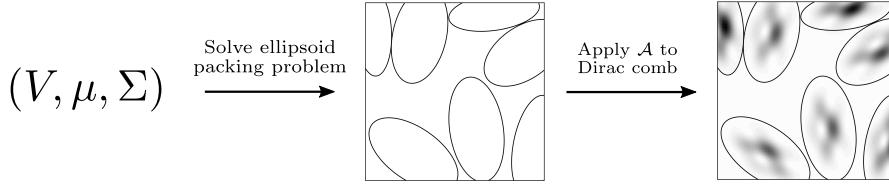


Fig. 4: Illustration of the process to compute one impulse response batch. Impulse response moments are first used to form ellipsoid shaped estimates of the supports of impulse responses (Equation 4.6). Then, an ellipsoid packing problem is solved to choose batches of non-overlapping support ellipsoids (Section 5.1). Finally, \mathcal{A} is applied to a Dirac comb associated with the points x_i , which correspond to the ellipsoids (Section 5.2). The process is repeated to form more batches.

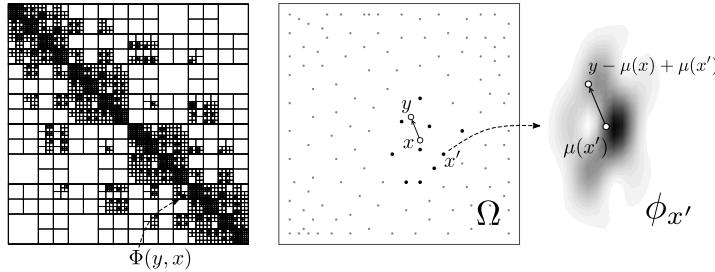


Fig. 5: Left: H-matrix structure for Φ . Computing an entry of this matrix requires evaluating the integral kernel, $\Phi(y, x)$, at a pair of points $(y, x) \in \Omega \times \Omega$. Center: Kernel evaluation points x and y (black circles), sample points for the approximation (light gray and black dots), and the k_n sample points, x' , that are nearest to x (black dots). Right: Known impulse response at x' . Using radial basis function interpolation, the desired kernel entry is approximated as a weighted linear combination of translated and scaled versions of impulse responses at the points x' (Section 5.3).

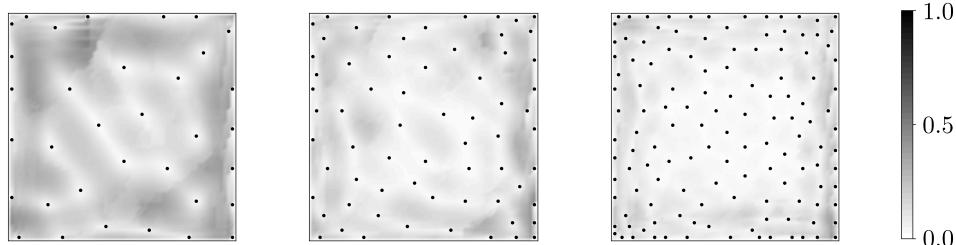


Fig. 6: Relative error, $\|\Phi(\cdot, x) - \tilde{\Phi}(\cdot, x)\|/\|\Phi(\cdot, x)\|$, in the approximation of the “column” of the integral kernel associated with x , using 5 (left), 10 (center) and 20 (right) impulse response batches. Sample points are indicated by black dots. The error associated with the point x is the shade of the image at location x , with white indicating zero error and black indicating 100% error. At the sample points, the error is zero. The further the point x is from the sample points, the larger the error. Adding more batches yields a more accurate approximation.

(PC) approximations, which are approximations of an operator by weighted sums of convolution operators with spatially varying weights. PC and PSF methods have a long history dating back several decades. We note the following papers (among many others) in which the convolution kernels are constructed from sampling impulse responses of the operator to scattered point sources: [1, 5, 12, 27, 29, 30, 32, 60, 78]. For background on PC and PSF methods, we recommend the following papers: [23, 28, 35]. The proposed PSF-based method improves upon existing PC and PSF methods in the following ways: (1) While PC and PSF approximations are typically based on an assumption of local translation invariance, the method we propose is based on a more general assumption we call “local mean displacement invariance” (Section 4.2 and Figure 1b), which improves the interpolation of the impulse responses. (2) In our previous work [5], we chose point sources in an adaptive grid via a sequential procedure; the refinements to the adaptive grid were chosen to maximally reduce the error at each step. However, in that work each point source required a separate operator application, making the previous method expensive when a large number of impulse responses is desired. In this paper, we use a new moment method (Section 4.1) which permits computation of many impulse responses (e.g., 50) per operator application. We are inspired by resolution analysis in seismic imaging, in which \mathcal{A}^T is applied to a random noise function, and the width of the support of ϕ_x is estimated to be the autocorrelation length of the resultant function near x [31, 74]. The moment method that we use estimates the support of ϕ_x more accurately than random noise probing in resolution analysis, at the cost of the additional constraint that \mathcal{A} has a non-negative integral kernel. (3) The PSF-based method we propose never evaluates computed impulse responses outside of their domain of definition. This eliminates “boundary-artifact” errors (see [5, Section 1.1]) that plague conventional PC and PSF methods.

The ability to rapidly approximate entries of \mathcal{A} ’s integral kernel allows one to approximate discretized versions of \mathcal{A} using the full arsenal of tools for matrix approximation that rely on fast access to matrix entries. In this work, we form a hierarchical matrix [13, 42] approximation of a discretized version of \mathcal{A} . H-matrices are a compressed matrix format in which the rows and columns of the matrix are re-ordered, then the matrix is recursively subdivided into blocks in such a way that many off-diagonal blocks are low rank, even though the matrix as a whole may be high rank. H-matrix methods permit us to perform matrix-vector products cheaply, and perform other useful linear algebra operations that cannot be done easily using the original operator. These operations include matrix-matrix addition, matrix-matrix multiplication, matrix factorization, and matrix inversion. The work and memory required to perform these operations for an $N \times N$ H-matrix with rank k_h blocks scales as $O(k_h^a N \log(N)^b)$ where $a, b \in \{0, 1, 2, 3\}$ are constants which depend on the type of H-matrix used and the operation being performed [40][52, Section 2.1].

2. Why we need more efficient approximations of high rank Hessians.

While the PSF-based method proposed in this paper may be used to approximate any operator that has a locally supported non-negative integral kernel, we are primarily motivated by approximation of high-rank Hessians in distributed parameter inverse problems governed by PDEs. In this section, we provide a brief background on this topic, and explain why existing Hessian approximation methods are not satisfactory.

In distributed parameter inverse problems governed by PDEs, one seeks to infer an unknown spatially varying parameter field from limited observations of a state variable that depends on the parameter implicitly through the solution of a PDE.

116 Conventionally, the inverse problem is formulated using either a deterministic frame-
 117 work [9, 76], or a Bayesian probabilistic framework [49, 70, 72]. In the deterministic
 118 framework, one solves an optimization problem to find the parameter that best fits
 119 the observations, subject to appropriate regularization [25, 76]. In the probabilistic
 120 framework, Bayes' theorem combines the observations with prior information to form
 121 a posterior distribution over the space of all possible parameter fields, and computa-
 122 tions are performed to extract statistical information about the parameter from this
 123 posterior. The Hessian of the objective function with respect to the parameter in the
 124 deterministic optimization problem and the Hessian of the negative log posterior in
 125 the Bayesian setting are equal or approximately equal under typical noise, regulariza-
 126 tion, and prior models, so we refer to both of these Hessians as “the Hessian.” The
 127 Hessian consists of a data misfit term (the *data misfit Hessian*), which depends on
 128 a discrepancy between the observations and the associated model predictions, and a
 129 regularization or prior term (the *regularization Hessian*) which does not depend on
 130 the observations. For more details on the Hessian, see [4, 38, 75].

131 Hessian approximations and preconditioners are highly desirable because the Hes-
 132 sian is central to efficient solution of inverse problems in both the deterministic and
 133 Bayesian settings. When solving the deterministic optimization problem with Newton-
 134 type methods, the Hessian is the coefficient operator for the linear system that must
 135 be solved or approximately solved at every Newton iteration. Good Hessian precondi-
 136 tioners reduce the number of iterations required to solve these Newton linear systems
 137 with the conjugate gradient method [66]. In the Bayesian setting, the inverse of the
 138 Hessian is the covariance of a local Gaussian approximation of the posterior. This
 139 Gaussian distribution can be used directly as an approximation of the posterior, or it
 140 can be used as a proposal for Markov chain Monte-Carlo methods for drawing samples
 141 from the posterior. For instance, see [50, 62] and the references therein.

142 Owing to the implicit dependence of predicted observations on the parameter,
 143 entries of the Hessian are not easily accessible. Rather, the Hessian may be applied to
 144 a vector via a computational process that involves solving a pair of forward and adjoint
 145 PDEs which are linearizations of the original PDE [38, 63]. The most popular matrix-
 146 free Hessian approximation methods are based on low rank approximation of either the
 147 data misfit Hessian, or the data misfit Hessian preconditioned by the regularization
 148 Hessian, e.g., [15, 19, 33, 62, 68]. Krylov methods such as Lanczos or randomized
 149 methods [18, 44] are typically used to construct these low rank approximations by
 150 applying the Hessian to vectors. Using these methods, the required number of Hessian
 151 applications (and hence the required number of PDE solves) is proportional to the
 152 rank of the low rank approximation. Low rank approximation methods are justified
 153 by arguing that the numerical rank of the data misfit Hessian is insensitive to the
 154 dimension of the discretized parameter. This means that the required number of
 155 PDE solves remains the same as the mesh used to discretize the parameter is refined.
 156 However, in many inverse problems of practical interest the numerical rank of the
 157 data misfit Hessian, while mesh independent, is still large, which makes it costly to
 158 approximate the Hessian using low rank approximation methods [7, 15, 48].

159 Examples of inverse problems with high rank data misfit Hessians include large-
 160 scale ice sheet inverse problems [45, 48], advection dominated advection-diffusion in-
 161 verse problems [2][34, Chapter 5], high frequency wave propagation inverse prob-
 162 lems [15], inverse problems governed by high Reynolds number flows, and more gen-
 163 erally, all inverse problems in which the observations highly inform the parameter.
 164 The eigenvalues of the data misfit Hessian characterize how informative the data are
 165 about components of the parameter in the corresponding eigenvector directions, hence

more informative data leads to larger eigenvalues and a larger numerical rank [3][4, Section 1.4 and Chapter 4]. Roughly speaking, the numerical rank of the data misfit Hessian is the dimension of the subspace of parameter space that is informed by the data. The numerical rank of the regularization preconditioned data misfit Hessian may be reduced by increasing the strength of the regularization, but this throws away useful information: components of the parameter that could be learned from the observations would instead be reconstructed based on the regularization [6, Section 4][76, Chapters 1 and 7]. Hence, low rank approximation methods suffer from a predicament: if the data highly inform the parameter and the regularization is chosen appropriately, then a large number of operator applications are required to form an accurate approximation of the Hessian using low rank approximation methods. High rank Hessian approximation methods are thus needed.

Recently there have been improvements in matrix-free H-matrix construction methods in which an operator is applied to structured random vectors, and the response of the operator to those random vectors is processed to construct an H-matrix approximation [54, 55, 57, 58, 59]. These methods (which we do not use here) have been used to approximate Hessians in PDE constrained inverse problems [7, 45]. Although these methods are promising, the required number of operator applications is still large (e.g., hundreds to thousands). For example, using the method in [55], the required number of operator applies to construct an H^1 matrix with hierarchical rank r for problems in a 2D domain discretized with a regular grid is $\# \text{levels} \cdot 64 \cdot (r + c)$, where $\# \text{levels}$ is the depth of the hierarchical partitioning, r is the rank of the blocks (hierarchical rank), and c is an oversampling parameter (see [55, Section 2.4]). On a 64×64 grid with depth 4, hierarchical rank 10, and oversampling parameter $c = 5$, this works out to $4 \cdot 64 \cdot (10 + 5) = 3840$ operator applies. In Section 7.3, we see numerically that the randomized hierarchical off-diagonal low rank (HODLR) method in [58] requires hundreds to thousands of matrix-vector products to construct approximations of the integral kernel for a blur problem example with modest (e.g., 10%) relative error. Matrix-free H-matrix construction is currently an active area of research, hence these costs may decrease as new algorithms are developed. In this paper, we also form an H-matrix approximation. However, to reduce the required number of operator applications, we first form a PSF approximation of the data misfit Hessian by exploiting locality and non-negative integral kernel properties, then form the H-matrix using classical techniques. Using this two stage approach, we reduce the number of operator applications to a few dozen at most.

Not all data misfit Hessians satisfy the local non-negative integral kernel properties. We note, in particular, that the wave inverse problem data misfit Hessian and Gauss-Newton Hessian have a substantial proportion of negative entries in their integral kernels. In this case more specialized techniques have been developed using, eg., pseudodifferential operator theory [21, 71], and sparsity in the wavelet domain [46]. However, many data misfit Hessians of practical interest do satisfy the local non-negative integral kernel properties (either exactly or approximately), and the PSF-based method we propose is targeted at approximating these Hessians.

3. Preliminaries. Let $\Omega \subset \mathbb{R}^d$ be a bounded domain (typically $d = 1, 2$, or 3). We seek to approximate integral operators $\mathcal{A} : L^2(\Omega) \rightarrow L^2(\Omega)'$ of the form

$$(3.1) \quad (\mathcal{A}u)(w) := \int_{\Omega} \int_{\Omega} w(y) \Phi(y, x) u(x) dx dy.$$

212 The linear functional $\mathcal{A}u \in L^2(\Omega)'$ is the result of applying \mathcal{A} to $u \in L^2(\Omega)$, and the
 213 scalar $(\mathcal{A}u)(w)$ is the result of applying that linear functional to $w \in L^2(\Omega)$. The
 214 integral kernel, $\Phi : \Omega \times \Omega \rightarrow \mathbb{R}$, exists but is not easily accessible. In this section we
 215 describe how to extend the domain of \mathcal{A} to distributions, which allows us to define
 216 impulse responses (Section 3.1), we then state the conditions on \mathcal{A} that the PSF-based
 217 method requires (Section 3.2), and detail finite element discretization (Section 3.3).

218 **3.1. Distributions and impulse responses.** The operator \mathcal{A} may be applied
 219 to distributions³ if Φ is sufficiently regular. Given $\rho \in L^2(\Omega)'$, let $\rho^* \in L^2(\Omega)$ denote
 220 the Riesz representative of ρ with respect to the $L^2(\Omega)$ inner product. We have

221 (3.2a)
$$(\mathcal{A}\rho^*)(w) = \int_{\Omega} \int_{\Omega} w(y)\Phi(y,x)\rho^*(x)dx dy$$

222 (3.2b)
$$= \int_{\Omega} w(y) \int_{\Omega} \Phi(y,x)\rho^*(x)dx dy = \int_{\Omega} w(y)\rho(\Phi(y,\cdot)) dy,$$

224 where $\Phi(y,\cdot)$ denotes the function $x \mapsto \Phi(y,x)$. Now let $\mathcal{D}(\Omega) \subset L^2(\Omega)$ be a suitable
 225 space of test functions and let $\rho : \mathcal{D}(\Omega) \rightarrow \mathbb{R}$ be a distribution. In this case, ρ^* may
 226 not exist, so the derivation in (3.2) is not valid. However, if Φ is sufficiently regular
 227 such that the function $y \mapsto \rho(\Phi(y,\cdot))$ is well-defined for almost all $y \in \Omega$, and if
 228 this function is in $L^2(\Omega)$, then the right hand side of (3.2b) is well-defined. Hence, we
 229 *define* the application of \mathcal{A} to the distribution ρ to be the right hand side of (3.2b).
 230 We denote this operator application by “ $\mathcal{A}\rho^*$,” even if ρ^* does not exist.

231 Let δ_x denote the delta distribution⁴ (i.e., point source, impulse) centered at the
 232 point $x \in \Omega$. The *impulse response* of \mathcal{A} associated with x is the function $\phi_x : \Omega \rightarrow \mathbb{R}$,

233 (3.3)
$$\phi_x := (\mathcal{A}\delta_x^*)^*,$$

234 that is formed by applying \mathcal{A} to δ_x (per the generalized notion of operator “appli-
 235 cation” defined above), then taking the Riesz representation of the resulting linear
 236 functional. Using (3.2b) and the definition of the delta distribution, we see that ϕ_x
 237 may also be written as the function $\phi_x(y) = \Phi(y,x)$.

238 **3.2. Required conditions.** We focus on approximating operators that satisfy
 239 the following conditions:

- 240 1. The kernel Φ is sufficiently regular so that ϕ_x is well-defined for all $x \in \Omega$.
 241 2. The supports of the impulse responses ϕ_x are contained in localized regions.
 242 3. The integral kernel is non-negative⁵ in the sense that

$$\Phi(y,x) \geq 0 \quad \text{for all } (y,x) \in \Omega \times \Omega.$$

243 The PSF-based method may still perform well if these conditions are relaxed slightly.

244 It is acceptable if the support of ϕ_x is not perfectly contained in a localized
 245 region (violating Assumption 2), so long as the bulk of the “mass” of ϕ_x is contained
 246 in a localized region. In principle, the PSF-based method can be applied even if the
 247 impulse responses are widely dispersed. However, in this case only a small number of
 248 impulse responses can be computed per batch, which means more batches, and hence
 more operator applies, are needed to form an accurate approximation.

³I.e., generalized functions such as the Dirac delta distribution. See, for example, [8, Chapter 5].

⁴Recall that the delta distribution $\delta_x : \mathcal{D}(\Omega) \rightarrow \mathbb{R}$ is defined by $\delta_x(w) = w(x)$ for all $w \in \mathcal{D}(\Omega)$.

⁵Note that having a non-negative integral kernel is different from positive semi-definiteness. The operator \mathcal{A} need not be positive semi-definite to use the PSF-based method, and positive semi-definite operators need not have a non-negative integral kernel.

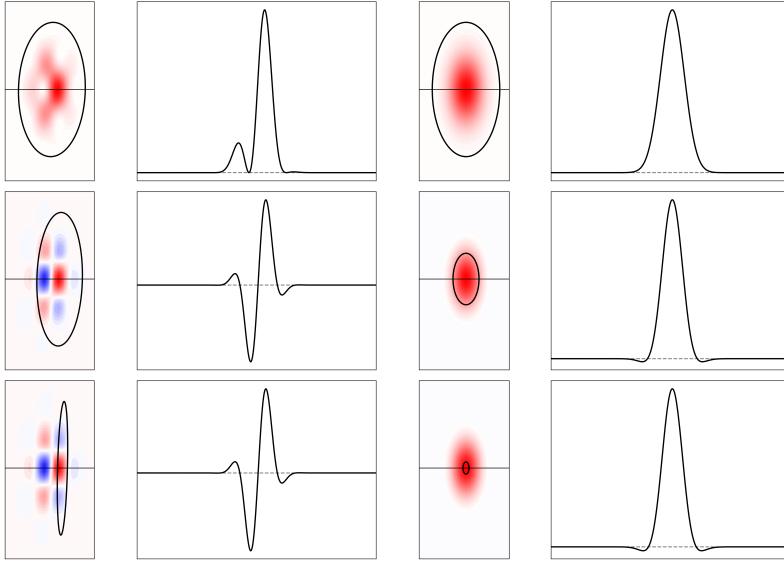


Fig. 7: Illustration of the influence of negative numbers in the integral kernel on the robustness of the ellipsoid estimates for the supports of impulse responses. Left two columns: Blur kernel given in Equation 7.4. Right two columns: Ricker wavelet-type kernel given by $\Phi(y, x) = (1 - a\gamma) \exp(-\gamma/2)$, where $\gamma = (y - x)^T \Sigma^{-1} (y - x)$, and $\Sigma = \text{diag}(0.0025, 0.01)$. Ordered from top to bottom, the results are obtained with $a \in \{1.0, 20.0, 27.0\}$ for the left two columns, and $a \in \{0.0, 0.23, 0.249\}$ for the right two columns. Columns 1 and 3: impulse responses with estimated support ellipsoids indicated by the black ellipses. Red and blue represent positive and negative numbers in the integral kernel, respectively. Columns 2 and 4: one-dimensional slice along the horizontal line indicated in the two-dimensional plots. The dashed gray line is at zero.

If there are negative numbers in the integral kernel (violating Assumption 3), the ellipsoid estimation procedure may incur errors or fail, leading to poor performance or failure of the PSF-based method. In Figure 7 we investigate the robustness of the ellipsoid support estimation procedure to violations of Assumption 3. We study two integral kernel examples, both of which are parameterized by a quantity that controls how negative the kernels are. We make the following observations:

- The larger and more numerous the negative numbers are, the more inaccurate the ellipsoid support estimate is.
- The further away from the center of the ellipsoid the negative numbers are, the more influence they have on the quality of the ellipsoid support estimate. This is because moment formulas (Equations 4.2 and 4.3) assign more weight to entries in the kernel that are further from the center.
- Negative numbers affect the ellipsoid estimation method more if they are isolated, and less if they are balanced by nearby positive numbers.
- As kernels become more negative, the ellipsoid estimation performs well up to a certain threshold that depends on the spatial distribution of negative and positive entries. After that threshold is crossed, the estimation rapidly transitions to performing poorly and ultimately failing.

267 For the kernel in the left two columns of Figure 7, negative numbers are interspersed
 268 with positive numbers, allowing us to include a large amount of negative numbers
 269 before the ellipsoid estimation fails. For the kernel in the right two columns, the
 270 ellipsoid estimate fails with tiny amounts of negative numbers because the negative
 271 numbers are far away from the mean and not balanced by positive numbers at similar
 272 distances and angles. In the bottom two rows, we see the aforementioned threshold
 273 effect, in which the ellipsoid estimation method rapidly transitions from performing
 274 reasonably well to performing poorly with only a small change to the integral kernel.

275 **3.3. Finite element discretization.** In computations, functions are discretized
 276 and replaced by finite-dimensional vectors, and operators mapping between infinite-
 277 dimensional spaces are replaced by operators mapping between finite-dimensional
 278 spaces. In this paper we discretize the functions that \mathcal{A} and \mathcal{A}^T are applied to using
 279 continuous finite elements satisfying the Kronecker property (defined below). With
 280 minor modifications, the PSF-based method could be used with more general finite
 281 element methods, or other discretization schemes such as finite differences or finite
 282 volumes. These restrictions on discretization only apply to functions u that \mathcal{A} and \mathcal{A}^T
 283 are applied to. Other functions that arise internally during the process of computing
 284 actions of \mathcal{A} , such as state variables in a PDE that is solved in a subproblem, may be
 285 discretized with any method.

286 Let $\psi_1, \psi_2, \dots, \psi_N$ be a set of continuous finite element basis functions used to dis-
 287 cretize the problem on a mesh with mesh size parameter h , let $V_h := \text{span}(\psi_1, \psi_2, \dots, \psi_N)$,
 288 be the corresponding finite element space under the L^2 inner product, and let $p_i \in \mathbb{R}^d$,
 289 $i = 1, \dots, N$ be the Lagrange nodes associated with the functions ψ_i . We assume
 290 that the finite element basis satisfies the Kronecker property, i.e., $\psi_i(p_i) = 1$ and
 291 $\psi_i(p_j) = 0$ if $i \neq j$. For $u_h \in V_h$ we write $\mathbf{u} \in \mathbb{R}_M^m$ to denote the coefficient vector
 292 for u_h with respect to the finite element basis, i.e., $u_h(x) = \sum_{i=1}^N \mathbf{u}_i \psi_i(x)$. Linear
 293 functionals $\rho_h \in V'_h$ have coefficient dual vectors $\boldsymbol{\rho} \in \mathbb{R}_{M-1}^m$, with entries $\boldsymbol{\rho}_i = \rho_h(\psi_i)$
 294 for $i = 1, \dots, m$. Here, $\mathbf{M} \in \mathbb{R}^{N \times N}$ denotes the sparse finite element mass matrix
 295 which has entries $\mathbf{M}_{ij} = \int_{\Omega} \psi_i(x) \psi_j(x) dx$ for $i, j = 1, \dots, N$. The space \mathbb{R}_M^N is \mathbb{R}^N
 296 with the inner product $(\mathbf{u}, \mathbf{w})_M := \mathbf{u}^T \mathbf{M} \mathbf{w}$, and \mathbb{R}_{M-1}^N is the analogous space with
 297 \mathbf{M}^{-1} replacing \mathbf{M} . Direct calculation shows that \mathbb{R}_M^N and \mathbb{R}_{M-1}^N are isomorphic to V_h
 298 and V'_h as Hilbert spaces, respectively.

299 After discretization, the operator $\mathcal{A} : L^2(\Omega) \rightarrow L^2(\Omega)'$ is replaced by an op-
 300 erator $A_h : V_h \rightarrow V'_h$, which becomes an operator $\mathbf{A} : \mathbb{R}_M^N \rightarrow \mathbb{R}_{M-1}^N$ under the
 301 isomorphism discussed above. The PSF-based method is agnostic to the computa-
 302 tional procedure for approximating \mathcal{A} with \mathbf{A} . What is important is that we do not
 303 have direct access to matrix entries \mathbf{A}_{ij} . Rather, we have a computational pro-
 304 cedure that allows us to compute matrix-vector products $\mathbf{u} \mapsto \mathbf{A}\mathbf{u}$ and $\mathbf{w} \mapsto \mathbf{A}^T\mathbf{w}$,
 305 and computing these matrix-vector products is costly. The PSF-based method mit-
 306 igates this cost by performing as few matrix-vector products as possible. Of course,
 307 matrix entries can be computed via matrix-vector products as $\mathbf{A}_{ij} = (\mathbf{A}\mathbf{e}_j)_i$, where
 308 $\mathbf{e}_j = (0, \dots, 0, 1, 0, \dots, 0)^T$ is the length N unit vector with one in the j th coordinate
 309 and zeros elsewhere. But computing the matrix-vector product $\mathbf{e}_j \mapsto \mathbf{A}\mathbf{e}_j$ is costly,
 310 and therefore wasteful if we do not use other matrix entries in the j th column of \mathbf{A} .
 311 Hence, methods for approximating \mathbf{A} are computationally intractable if they require
 312 accessing scattered matrix entries from many different rows and columns of \mathbf{A} .

313 The operator $A_h : V_h \rightarrow V'_h$ can be written in integral kernel form, (3.1), but
 314 with Φ replaced by a slightly different integral kernel, Φ_h , which we do not know,
 315 and which differs from Φ due to discretization error. Since the functions in V_h are

continuous at x , the delta distribution δ_x is a continuous linear functional on V_h , which has a discrete dual vector $\boldsymbol{\delta}_x \in \mathbb{R}_{\mathbf{M}^{-1}}^N$ with entries $(\boldsymbol{\delta}_x)_i = \psi_i(x)$ for $i = 1, \dots, N$. Additionally, it is straightforward to verify that the Riesz representation, $\rho_h^* \in V_h$, of a functional $\rho \in V_h'$ has coefficient vector $\boldsymbol{\rho}^* = \mathbf{M}^{-1}\boldsymbol{\rho}$. Therefore, the formula for the impulse response from (3.3) becomes $\phi_x = (A_h \boldsymbol{\delta}_x)^* = \mathbf{M}^{-1} \mathbf{A} \mathbf{M}^{-1} \boldsymbol{\delta}_x$, and the (y, x) kernel entry of Φ_h may be written as $\Phi_h(y, x) = \boldsymbol{\delta}_y^T \phi_x = \boldsymbol{\delta}_y^T \mathbf{M}^{-1} \mathbf{A} \mathbf{M}^{-1} \boldsymbol{\delta}_x$. Now define $\boldsymbol{\Phi} \in \mathbb{R}^{N \times N}$ to be the following dense matrix of kernel entries evaluated at all pairs of Lagrange nodes:

$$(3.4) \quad \boldsymbol{\Phi}_{ij} := \Phi_h(p_i, p_j).$$

Because of the Kronecker property of the finite element basis, we have $\boldsymbol{\delta}_{p_i} = \mathbf{e}_i$. Thus, we have $\Phi_h(p_i, p_j) = (\mathbf{M}^{-1} \mathbf{A} \mathbf{M}^{-1})_{ij}$, which implies

$$(3.5) \quad \mathbf{A} = \mathbf{M} \boldsymbol{\Phi} \mathbf{M}.$$

Broadly, we will construct an H-matrix approximation of \mathbf{A} by forming an H-matrix approximation of $\boldsymbol{\Phi}$, then multiplying $\boldsymbol{\Phi}$ by \mathbf{M} (or a lumped mass version of \mathbf{M}) on the left and right using H-matrix methods. Classical H-matrix construction methods require access to arbitrary matrix entries $\boldsymbol{\Phi}_{ij}$, but these matrix entries are not easily accessible. The bulk of the PSF-based method is therefore dedicated to forming approximations of these matrix entries that can be evaluated rapidly.

Lumped mass matrix. At the continuum level, $\boldsymbol{\Phi}$ is assumed to be non-negative. However, entries of $\boldsymbol{\Phi}$ involve inverse mass matrices, which typically contain negative numbers. We therefore recommend replacing the mass matrix, \mathbf{M} , with a positive diagonal *lumped mass* approximation. Here, we use the lumped mass matrix in which the i th diagonal entry of the lumped mass matrix is the sum of all entries in the i th row of the mass matrix. Other mass lumping techniques may be used.

4. Key innovations. In this section we present two key innovations that the PSF-based method is based on. First, we define moments of the impulse responses, ϕ_x , show how these moments can be computed efficiently, and use these moments to form ellipsoid shaped a-priori estimates for the supports of the impulse responses (Section 4.1). Second, we describe an improved method to approximate impulse responses from other nearby impulse responses, which we call “normalized local mean displacement invariance” (Section 4.2).

4.1. Impulse response moments and ellipsoid support estimate. The impulse response ϕ_x may be interpreted as a scaled probability distribution because of the non-negative integral kernel property. Let $V : \Omega \rightarrow \mathbb{R}$,

$$(4.1) \quad V(x) := \int_{\Omega} \phi_x(y) dy,$$

denote the spatially varying scaling factor, and for $i, j = 1, \dots, d$ define $\mu : \Omega \rightarrow \mathbb{R}^d$ and $\Sigma : \Omega \rightarrow \mathbb{R}^{d \times d}$ as follows:

$$(4.2) \quad \mu^i(x) := \frac{1}{V(x)} \int_{\Omega} \phi_x(y) y^i dy$$

$$(4.3) \quad \Sigma^{ij}(x) := \frac{1}{V(x)} \int_{\Omega} \phi_x(y) (y^i - \mu^i(x)) (y^j - \mu^j(x)) dy,$$

356 where $\mu^i(x)$ and y^i denote the i^{th} components of the vectors $\mu(x)$ and y , respectively,
 357 and $\Sigma^{ij}(x)$ denotes the (i, j) entry of the matrix $\Sigma(x)$. The quantities $\mu(x) \in \mathbb{R}^d$ and
 358 $\Sigma(x) \in \mathbb{R}^{d \times d}$ are the mean and covariance of the normalized version of ϕ_x , respectively.

359 The direct approach to compute $V(x)$, $\mu(x)$, and $\Sigma(x)$ is to apply \mathcal{A} to a point
 360 source centered at x to obtain ϕ_x , per (3.3). Then one can post process ϕ_x to determine
 361 $V(x)$, $\mu(x)$, and $\Sigma(x)$. However, this direct approach is not feasible because our
 362 algorithm for picking sample points (Section 5.1 and Figure 4) needs to know $V(x)$,
 363 $\mu(x)$, and $\Sigma(x)$ before we compute ϕ_x . Computing ϕ_x in order to determine $V(x)$,
 364 $\mu(x)$, and $\Sigma(x)$ would be extremely computationally expensive, and defeat the purpose
 365 of the PSF-based method, which is to reduce the computational cost by computing
 366 impulse responses in batches. Fortunately, it is possible to compute $V(x)$, $\mu(x)$, and
 367 $\Sigma(x)$ indirectly, *for all points $x \in \Omega$ simultaneously*, by applying \mathcal{A}^T to one constant
 368 function, d linear functions, and $d(d+1)/2$ quadratic functions (e.g., 6 total operator
 369 applications in two spatial dimensions and 10 in three spatial dimensions). This may
 370 be motivated by analogy to matrices. If $\mathbf{A} \in \mathbb{R}^{N \times N}$ is a matrix with i^{th} column \mathbf{a}_i
 371 and $\mathbf{w} \in \mathbb{R}^N$, then

$$372 \quad \mathbf{A}^T \mathbf{w} = \begin{bmatrix} - & \mathbf{a}_1^T & - \\ \vdots & & \vdots \\ - & \mathbf{a}_N^T & - \end{bmatrix} \mathbf{w} = \begin{bmatrix} \mathbf{a}_1^T \mathbf{w} \\ \vdots \\ \mathbf{a}_N^T \mathbf{w} \end{bmatrix}.$$

373 By computing one matrix-vector product of \mathbf{A}^T with \mathbf{w} , we compute the inner product
 374 of each column of \mathbf{A} with \mathbf{w} simultaneously. The operator case is analogous, with ϕ_x
 375 taking the place of a matrix column. We have

$$376 \quad (4.4) \quad (\mathcal{A}^T w)^*(x) = \int_{\Omega} \Phi(y, x) w(y) dy = (\phi_x, w)_{L^2(\Omega)}.$$

377 By computing one operator application of \mathcal{A}^T to w , we compute the inner product of
 378 each ϕ_x with w , for all points x simultaneously.

379 Let C , L^i , and Q^{ij} be the following constant, linear, and quadratic functions:

$$380 \quad C(x) := 1, \quad L^i(x) := x^i, \quad Q^{ij}(x) := x^i x^j$$

381 for $i, j = 1, \dots, d$. Using the definition of V in (4.1) and using (4.4), we have

$$382 \quad V(x) = \int_{\Omega} \phi_x(y) C(y) dy = (\phi_x, C)_{L^2(\Omega)} = (\mathcal{A}^T C)^*(x).$$

383 Hence, we compute $V(x)$ for all x simultaneously by applying \mathcal{A}^T to C . Analogous
 384 manipulations show that $\mu(x)$ and $\Sigma(x)$ may be computed for all points x simultane-
 385 ously by applying \mathcal{A}^T to the functions L^i and Q^{ij} , respectively. We have

$$386 \quad (4.5a) \quad V = (\mathcal{A}^T C)^*$$

$$387 \quad (4.5b) \quad \mu^i = (\mathcal{A}^T L^i)^*/V$$

$$388 \quad (4.5c) \quad \Sigma^{ij} = (\mathcal{A}^T Q^{ij})^*/V - \mu^i \cdot \mu^j$$

390 for $i, j = 1, \dots, d$. Here, u/w denotes pointwise division, $(u/w)(x) = u(x)/w(x)$, and
 391 $u \cdot w$ denotes pointwise multiplication, $(u \cdot w)(x) = u(x)w(x)$.

392 We approximate the support of ϕ_x with the ellipsoid

$$393 \quad (4.6) \quad E_x := \{x' \in \Omega : (x' - \mu(x))^T \Sigma(x)^{-1} (x' - \mu(x)) \leq \tau^2\},$$

394 where τ is a fixed constant (see Figure 3). The ellipsoid E_x is the set of points
 395 within τ standard deviations of the mean of the Gaussian distribution with mean
 396 $\mu(x)$ and covariance $\Sigma(x)$, i.e., the Gaussian distribution which has the same mean
 397 and covariance as the normalized version of ϕ_x . The quantity τ is a parameter that
 398 must be chosen appropriately. The larger τ is, the larger the ellipsoid E_x is, and the
 399 more conservative the estimate is for the support of ϕ_x . However, in Section 5.1 we
 400 will see that the cost of the PSF-based method depends on how many non-overlapping
 401 ellipsoids E_x we can “pack” in the domain Ω (more ellipsoids is better), and choosing
 402 a larger value of τ means that fewer ellipsoids will fit in Ω . In practice, we find
 403 that $\tau = 3.0$ yields a reasonable balance between these competing interests, and use
 404 $\tau = 3.0$ in all numerical results, except for Figure 14, where we study the effects of
 405 varying τ . The fraction of the “mass” of ϕ_x residing outside of E_x is less than $1/\tau^2$
 406 by Chebyshev’s inequality, though this bound is typically conservative.

407 **4.2. Local mean displacement invariance.** Let x and x' be points in Ω that
 408 are close to each other, and consider the following approximations:

$$409 \quad (4.7) \quad \phi_x(y) \approx \phi_{x'}(y)$$

$$410 \quad (4.8) \quad \phi_x(y) \approx \phi_{x'}(y - x + x')$$

$$411 \quad (4.9) \quad \phi_x(y) \approx \phi_{x'}(y - \mu(x) + \mu(x'))$$

$$413 \quad (4.10) \quad \phi_x(y) \approx \phi_{x'}(y - \mu(x) + \mu(x')) V(x)/V(x').$$

414 These are four different ways to approximate an impulse response by a nearby impulse
 415 response, with each successive approximation building upon the previous ones. The
 416 PSF-based method uses (4.10), which is the most sophisticated. Approximation (4.7)
 417 says that ϕ_x can be approximated by $\phi_{x'}$ when x and x' are close. Operators satisfying
 418 (4.7) can be well approximated via low rank CUR approximation. However, the
 419 required rank in the low rank approximation can be large, which makes algorithms
 420 based on (4.7) expensive. Operators that satisfy (4.8) are called “locally translation
 421 invariant” because integral kernel entries $\Phi(y, x)$ for such operators are approximately
 422 invariant under translation of x and y by the same displacement, i.e., $x \rightarrow x + h$ and
 423 $y \rightarrow y + h$. It is straightforward to show that if equality holds in (4.8), then \mathcal{A} is
 424 a convolution operator. Locally translation invariant operators act like convolutions
 425 locally, and can therefore be well approximated by PC approximations.

426 Approximation (4.9) improves upon (4.7) and (4.8), and generalizes both. On one
 427 hand, if (4.7) holds, then $\mu(x) \approx \mu(x')$, and so (4.9) holds. On the other hand, trans-
 428 lating a distribution translates its mean, so if (4.8) holds, then $\mu(x') - \mu(x) \approx x' - x$, so
 429 again (4.9) holds. But approximation (4.9) can hold in situations where neither (4.7)
 430 nor (4.8) holds. For example, because the expected value commutes with affine trans-
 431 formations, (4.9) will hold when \mathcal{A} is locally translation invariant with respect to a
 432 translated and rotated frame of reference, while (4.8) will not. Additionally, (4.9)
 433 generalizes to operators $\mathcal{A} : L^2(\Omega_1) \rightarrow L^2(\Omega_2)'$ that map between function spaces on
 434 different domains Ω_1 and Ω_2 , and even operators that map between domains with
 435 different spatial dimensions. In contrast, (4.8) does not naturally generalize to op-
 436 erators that map between function spaces on different domains, because the formula
 437 $y - x + x'$ requires vectors in Ω_2 and Ω_1 to be added together. We call (4.9) “local
 438 mean displacement invariance,” and illustrate (4.9) in Figure 1b.

439 We use approximation (4.10), which is the same as (4.9), except for the factor
 440 $V(x)/V(x')$. This factor makes the approximation more accurate if $V(x)$ varies widely.
 441 Approximation (4.10) is equivalent to (4.9), but with ϕ_x replaced by its normalized
 442 version, $\phi_x/V(x)$. We call (4.10) *normalized local mean displacement invariance*.

443 **5. Operator approximation algorithm.** Before presenting the technical details of the algorithm in Sections 5.1–5.5, we first provide an overview.

444 We use (4.5) to compute V , μ , and Σ by applying \mathcal{A}^T to polynomial functions.
 445 Then we use (4.6) to form ellipsoid shaped estimates for the support of the ϕ_x 's,
 446 *without* computing them (see Figure 3). This allows us to compute large numbers
 447 of ϕ_{x_i} in “batches,” η_b (see Figures 1a and 4). We compute one batch, denoted η_b ,
 448 by applying \mathcal{A} to a weighted sum of point sources (Dirac comb) associated with a
 449 batch, S_b , of points x_i scattered throughout Ω (Section 5.2). The batch of points,
 450 S_b , is chosen via a greedy ellipsoid packing algorithm so that, for $x_i, x_j \in S_b$, the
 451 support ellipsoid for ϕ_{x_i} and the support ellipsoid for ϕ_{x_j} do not overlap if $i \neq j$
 452 (Section 5.1). Because these supports do not overlap (or do not overlap much), we
 453 can post process η_b to recover the functions ϕ_{x_i} associated with all points $x_i \in S_b$.
 454 With one application of \mathcal{A} , we recover many ϕ_{x_i} (Section 5.2). The process is repeated
 455 until a desired number of batches is reached.

456 Once the batches η_b are computed, we approximate the integral kernel $\Phi(y, x)$
 457 at arbitrary points (y, x) by interpolation of translated and scaled versions of the
 458 computed ϕ_{x_i} (Section 5.3 and Figure 5). The key idea behind the interpolation is the
 459 normalized local mean displacement invariance assumption discussed in Section 4.2.
 460 Specifically, we approximate $\Phi(y, x) = \phi_x(y)$ by a weighted linear combination of the
 461 values $\frac{V(x)}{V(x_i)}\phi_{x_i}(y - \mu(x) + \mu(x_i))$ for a small number of sample points x_i near x . The
 462 weights are determined by radial basis function (RBF) interpolation.

463 The ability to rapidly evaluate approximate kernel entries $\Phi(y, x)$ allows us to
 464 construct an H-matrix approximation, $\Phi_H \approx \Phi$, using the conventional adaptive
 465 cross H-matrix construction method (Section 5.4). In this method, one forms low rank
 466 approximations of off-diagonal blocks of the matrix by sampling rows and columns of
 467 those blocks. We then convert Φ_H into an H-matrix approximation $\mathbf{A}_H \approx \mathbf{A}$.

468 When \mathcal{A} is symmetric positive semi-definite, \mathbf{A}_H may be non-symmetric and
 469 indefinite due to errors in the approximation. In this case, one may optionally sym-
 470 metrize \mathbf{A}_H , then modify it via low rank updates to remove erroneous negative ei-
 471 genvalues (Section 5.5). The complete algorithm for constructing \mathbf{A}_H is shown in
 472 Algorithm 1. The computational cost is discussed in Section 6.

Algorithm 1: Construct PSF H-matrix approximation

Input : Linear operator \mathcal{A} , parameter n_b

Output: H-matrix \mathbf{A}_H

- 1 Compute V, μ , and Σ (Equations (4.5) in Section 4.1)
 - 2 **for** $k = 1, 2, \dots, n_b$ **do**
 - 3 Choose a batch of sample points, S_k (Section 5.1)
 - 4 Compute impulse response batch η_k by applying \mathcal{A} to the Dirac comb for
 S_k (Section 5.2)
 - 5 Form H-matrix approximation Φ_H of integral kernel (Sections 5.3 and 5.4)
 - 6 Form H-matrix approximation \mathbf{A}_H of \mathcal{A} (Section 5.4)
 - 7 (optional) Modify \mathbf{A}_H to make it symmetric and remove negative
eigenvalues (Section 5.5)
-

474 **5.1. Sample point selection via greedy ellipsoid packing.** We choose sam-
 475 ple points, x_i , in batches S_k . We use a greedy ellipsoid packing algorithm to choose
 476 as many points as possible per batch, while ensuring that there is no overlap between

477 the support ellipsoids, E_{x_i} , associated with the sample points within a batch.

478 We start with a finite set of candidate points X and build S_k incrementally with
 479 points selected from X . For simplicity of explanation, here S_k and X are mutable
 480 sets that we add points to and remove points from. First we initialize S_k as an empty
 481 set. Then we select the candidate point $x_i \in X$ that is the farthest away from all
 482 points in previous sample point batches $S_1 \cup S_2 \cup \dots \cup S_{k-1}$. Candidate points for the
 483 first batch S_1 are chosen randomly from X . Once x_i is selected, we remove x_i from
 484 X . Then we perform the following checks:

- 485 1. We check whether x_i is sufficiently far from all of the previously chosen points
 486 in the current batch, in the sense that $E_{x_i} \cap E_{x_j} = \{\}$ for all $x_j \in S_k$.
- 487 2. We make sure that $V(x_i)$ is not too small, by checking whether $V(x_i) >$
 488 $\epsilon_V V_{\max}$. Here, V_{\max} is the largest value of $V(x_j)$ over all points q in the
 489 initial set of candidate points, and ϵ_V is a small threshold parameter (we use
 490 $\epsilon_V = 10^{-5}$).
- 491 3. We make sure that all eigenvalues of $\Sigma(x_i)$ are positive, and the aspect ratio of
 492 E_{x_i} (square root of the ratio of the largest eigenvalue of $\Sigma(x_i)$ to the smallest)
 493 is bounded by a constant $1/\epsilon_\Sigma$ (we use $1/\epsilon_\Sigma = 20$). Negative integral kernel
 494 entries due to discretization error can cause $\Sigma(x_i)$ to be indefinite or highly
 495 ill-conditioned.

496 If x_i passes these checks then we add x_i to S_k . Otherwise we discard x_i . This process
 497 repeats until there are no more points in X . We repeat the point selection process to
 498 construct several batches of points S_1, S_2, \dots, S_{n_b} . For each batch, X is initialized as
 499 the set of all Lagrange nodes for the finite element basis functions used to discretize
 500 the problem, except for points in previous batches.

501 We check whether $E_{x_i} \cap E_{x_j} = \{\}$ in a two stage process. First, we check whether
 502 the axis aligned bounding boxes for the ellipsoids intersect. This quickly rules out
 503 intersections of ellipsoids that are far apart. Second, if the bounding boxes intersect,
 504 we check if the ellipsoids intersect using the ellipsoid intersection test in [39].

505 **5.2. Impulse response batches.** We compute impulse responses, ϕ_{x_i} , in batches■
 506 by applying \mathcal{A} to Dirac combs. The Dirac comb, ξ_k , associated with a batch of sam-
 507 ple points, S_k , is the following weighted sum of Dirac distributions (point sources)
 508 centered at the points $x_i \in S_k$:

$$509 \quad \xi_k := \sum_{x_i \in S_k} \delta_{x_i} / V(x_i).$$

510 We compute the *impulse response batch*, η_k , by applying \mathcal{A} to the Dirac comb:

$$511 \quad (5.1) \quad \eta_k := (\mathcal{A}\xi_k^*)^* = \sum_{x_i \in S_k} \phi_{x_i} / V(x_i).$$

512 The last equality in (5.1) follows from linearity and the definition of ϕ_{x_i} in (3.3). Since
 513 the points x_i are chosen so that the ellipsoid E_{x_i} that (approximately) supports ϕ_i ,
 514 and the ellipsoid E_{x_j} that (approximately) supports ϕ_j do not overlap when $i \neq j$,
 515 we have (approximately)

$$516 \quad (5.2) \quad \phi_{x_i}(z) = \begin{cases} \eta_k(z)V(x_i), & z \in E_{x_i} \\ 0, & \text{otherwise} \end{cases}$$

517 for all $x_i \in S_k$. By applying the operator once, $\xi_k \mapsto (\mathcal{A}\xi_k^*)^*$, we recover ϕ_{x_i} for every
 518 point $x_i \in S_k$.

519 Each point source, δ_{x_i} , is scaled by $1/V(x_i)$ so that the resulting scaled impulse
 520 responses within η_k are comparable in magnitude. Without this scaling, the portion
 521 of ϕ_{x_i} outside of E_{x_i} , which we neglect, may overwhelm ϕ_{x_j} for a nearby point x_j
 522 if $V(x_i)$ is much larger than $V(x_j)$. Note that we are not in danger of dividing
 523 by zero, because the ellipsoid packing procedure from Section 5.1 excludes x_i from
 524 consideration as a sample point if $V(x_i)$ is smaller than a predetermined threshold.

525 **5.3. Approximate integral kernel entries.** Here, we describe how to rapidly
 526 evaluate arbitrary entries of an approximation to the integral kernel by performing
 527 radial basis function interpolation of translated and scaled versions of nearby known
 528 impulse responses. In Section 5.4 we use this procedure for rapidly evaluating kernel
 529 entries to construct the H-matrix approximation of \mathbf{A} .

530 Given $(y, x) \in \Omega \times \Omega$, let $z_i := y - \mu(x) + \mu(x_i)$ and define

$$531 \quad (5.3) \quad f_i := \frac{V(x)}{V(x_i)} \phi_{x_i}(z_i)$$

532 for $i = 1, \dots, k_n$, where $\{x_i\}_{i=1}^{k_n}$ are the k_n nearest sample points to x , excluding
 533 points x_i for which $z_i \notin \Omega$. Here, k_n is a small user-defined parameter, e.g., $k_n = 10$.
 534 We find the k_n nearest sample points to x by querying a precomputed kd-tree [11] of
 535 all sample points. We check whether $z_i \in \Omega$ by querying a precomputed axis aligned
 536 bounding box tree (AABB tree) [26] of the mesh cells used to discretize the problem.
 537 Note that $\phi_{x_i}(z_i)$ is well-defined because $z_i \in \Omega$, and $\frac{V(x)}{V(x_i)}$ is well-defined because
 538 the sample point choosing procedure in Section 5.1 ensures that $V(x_i) > 0$. Per the
 539 discussion in Section 4.2, we expect $\Phi(y, x) \approx f_i$ for $i = 1, \dots, k_n$. The closer x_i is to
 540 x , the better we expect the approximation to be. We therefore approximate $\Phi(y, x)$
 541 by interpolating the (point,value) pairs $\{(x_i, f_i)\}_{i=1}^{k_n}$ at the point x . Interpolation is
 542 performed using the following radial basis function [77] scheme:

$$543 \quad (5.4) \quad \Phi(y, x) \approx \tilde{\Phi}(y, x) := \sum_{i=1}^{k_n} c_i \varphi(\|x - x_i\|),$$

544 where c_i are weights, and $\varphi(r) := \exp\left(-\frac{1}{2}\left(C_{\text{RBF}} \frac{r}{r_0}\right)^2\right)$ is a Gaussian kernel radial
 545 basis function. Here, $r_0 := \text{diam}\left(\{x_i\}_{i=1}^{k_n}\right)$ is the diameter of the set of sample points
 546 used in the interpolation, and C_{RBF} is a user-defined shape parameter that controls
 547 the width of the kernel function. The vector of weights, $c = (c_1, c_2, \dots, c_{k_n})^T$, is found
 548 as the solution to the $k_n \times k_n$ linear system

$$549 \quad (5.5) \quad Bc = f,$$

550 where $B \in \mathbb{R}^{k_n \times k_n}$, $B_{ij} := \varphi(\|x_i - x_j\|)$, and $f \in \mathbb{R}^{k_n}$ has entries f_i from (5.3).

551 To evaluate f_i , we check whether $z_i \in E_{x_i}$ using (4.6). If $z_i \notin E_{x_i}$, then z_i is
 552 outside the estimated support of ϕ_{x_i} , so we set $f_i = 0$. If $z_i \in E_{x_i}$, we look up the
 553 batch index b such that $x_i \in S_b$, and evaluate f_i via the formula $f_i = V(x)\eta_b(z_i)$,
 554 per (5.2). Note that z_i is typically not a gridpoint of the mesh used to discretize
 555 the problem, even if y , x , and x_i are gridpoints. Hence, evaluating $\eta_b(z_i)$ requires
 556 determining which mesh cell contains z_i , then evaluating finite element basis functions
 557 on that mesh cell. Fortunately, the mesh cell containing z_i was determined as a side
 558 effect of querying the AABB tree of mesh cells when we checked whether $z_i \in \Omega$.

559 The shape parameter, C_{RBF} , mediates a tradeoff between accuracy and stability.
 560 Small C_{RBF} is required for RBF interpolation with Gaussian kernels to achieve high
 561 accuracy, but small C_{RBF} also makes RBF interpolation less robust to errors or non-
 562 smoothness in the function being interpolated. For our numerical results involving
 563 Hessians in inverse problems governed by PDEs (Sections 7.1 and 7.2), high accuracy
 564 is not required because the PSF-based method is used to construct a preconditioner.
 565 Hence, for these Hessian approximations we use a conservative choice of $C_{\text{RBF}} = 3.0$
 566 to ensure robustness. For our numerical results for the blur problem example (Sec-
 567 tion 7.3), we use a smaller value of $C_{\text{RBF}} = 0.5$ so that the RBF interpolation accuracy
 568 is not a limiting factor as we study convergence of the PSF-based method.

569 **5.4. Hierarchical matrix construction.** We form an H-matrix approximation
 570 $\mathbf{A}_H \approx \mathbf{A}$ by forming an H-matrix representation Φ_H of Φ then multiplying Φ with
 571 mass matrices \mathbf{M} per (3.5) to form $\mathbf{A}_H = \mathbf{M}\Phi_H\mathbf{M}$. Here, we use a diagonal lumped
 572 mass matrix, so these matrix-matrix multiplications are trivial. If a non-diagonal
 573 mass matrix is used, one may form an H-matrix representation of the mass matrix,
 574 then perform the matrix-matrix multiplications in (3.5) using H-matrix methods. We
 575 use H1 matrices in the numerical results, but any other H-matrix format could be
 576 used instead. For more details on H-matrices, see [43].

577 We form Φ_H using the standard geometrical clustering/adaptive cross method im-
 578 plemented within the HLIBpro software package [51]. For details about the algorithms
 579 used for geometrical clustering, H-matrix construction, and H-matrix operations in
 580 HLIBpro, we refer the reader to [13, 41, 52]. Although Φ is a dense $N \times N$ matrix, con-
 581 structing Φ_H only requires evaluation of $O(k_h N \log N)$ kernel entries $\Phi_{ij} = \tilde{\Phi}(p_i, p_j)$
 582 (see [10]), and these entries are computed via the radial basis function interpolation
 583 method described in Section 5.3. Here, k_h is the rank of the highest rank block in the
 584 H-matrix. We emphasize that the dense matrix Φ is never formed.

585 **5.5. Symmetrizing and flipping negative eigenvalues (optional).** In many
 586 applications, one seeks to approximate an operator $\mathcal{H} = \mathcal{A} + \mathcal{R}$, where \mathcal{A} is a symmet-
 587 ric positive semi-definite operator that we approximate with the PSF-based method
 588 to form an H-matrix \mathbf{A}_H , and \mathcal{R} is a symmetric positive definite operator that may
 589 be easily converted to an H-matrix \mathbf{R}_H without using the PSF-based method. For
 590 example, in inverse problems \mathcal{H} is the Hessian, \mathcal{A} is the data misfit term in the Hes-
 591 sian which is dense and available only matrix-free, and \mathcal{R} is the regularization term,
 592 which is typically an elliptic differential operator that becomes a sparse matrix after
 593 discretization.

594 The PSF-based approximation \mathbf{A}_H , and therefore $\mathbf{A}_H + \mathbf{R}_H$, may be non-symmetric
 595 and indefinite because of approximation error. This is undesirable because symmetry
 596 and positive semi-definiteness are important properties which should be preserved if
 597 possible. Also, lacking these properties may prevent one from using highly effective
 598 algorithms to perform further operations involving $\mathbf{A}_H + \mathbf{R}_H$, such as using $\mathbf{A}_H + \mathbf{R}_H$
 599 as a preconditioner in the conjugate gradient method.

600 We modify \mathbf{A}_H to make it symmetric and remove negative eigenvalues via the
 601 following procedure. First, we symmetrize \mathbf{A}_H via $\mathbf{A}_H^{\text{sym}} := \frac{1}{2}(\mathbf{A}_H + \mathbf{A}_H^T)$. Next,
 602 we find negative eigenvalues and their corresponding eigenvectors for the generalized
 603 eigenvalue problem $\mathbf{A}_H^{\text{sym}}\mathbf{u} = \lambda\mathbf{R}_H$ using a Cayley shift-and-invert Krylov scheme [53].
 604 We flip the signs of these eigenvalues to be positive instead of negative (i.e., $\lambda \rightarrow |\lambda|$)
 605 by performing a low rank update to $\mathbf{A}_H^{\text{sym}}$. We observe that the eigenvectors associated
 606 with large erroneous negative eigenvalues tend to be directions that are nevertheless
 607 “important” to \mathcal{A} , so flipping the eigenvalues instead of setting them to zero tends to

Symbol	Typical size	Variable name
N	$10^3\text{--}10^9$	Number of finite element degrees of freedom
n_b	1–25	Number of batches
k_h	5–50	H-matrix rank
k_n	5–15	Number of nearest neighbors for RBF interpolation
d	1–3	Spatial dimension
m	$10^1\text{--}10^4$	Total number of sample points (all batches)
$ S_i $	1–500	Number of sample points in the i th batch

Table 1: Symbols used for variables in computational cost estimates, and approximate ranges for their sizes in practice.

608 yield better approximations. The primary computational task in the Cayley shift-and-
 609 invert scheme is the solution of shifted linear systems of the form $(\mathbf{A}_H^{\text{sym}} + \mu_i \mathbf{R}_H) \mathbf{x} =$
 610 \mathbf{b} , for a small number of positive shifts μ_i . We solve these linear systems by factorizing
 611 the matrices $\mathbf{A}_H^{\text{sym}} + \mu_i \mathbf{R}_H$ using fast H-matrix methods. We compute and flip all
 612 eigenvalues $\lambda < \epsilon_{\text{flip}}$ which are less than some threshold $\epsilon_{\text{flip}} \in (-1, 0]$. By choosing
 613 $\epsilon_{\text{flip}} > -1$, we ensure that the modified version of $\mathbf{A}_H^{\text{sym}} + \mathbf{R}_H$ is positive definite.
 614 Choosing $\epsilon_{\text{flip}} = 0$ would remove all erroneous negative eigenvalues. However, this
 615 is computationally infeasible if \mathcal{A} has a large or infinite cluster of eigenvalues near
 616 zero, a common situation for Hessians in ill-posed inverse problems. We therefore
 617 recommend choosing $\epsilon_{\text{flip}} < 0$. In our numerical results, we use $\epsilon_{\text{flip}} = -0.1$.

618 **6. Computational cost.** The computational cost of the PSF-based method
 619 may be divided into the costs to perform the following tasks: (1) Computing impulse
 620 response moments and batches (Lines 1 and 4 in Algorithm 1); (2) Building the
 621 H-matrix (Lines 5 and 6 in Algorithm 1); (3) Performing linear algebra operations
 622 with the H-matrix. This may optionally include the symmetric positive semi-definite
 623 modifications described in Section 5.5. In target applications, (1) is the dominant
 624 cost because applying \mathcal{A} to a vector requires an expensive computational procedure
 625 such as solving a PDE, and (1) is the only step that requires applying \mathcal{A} to vectors.
 626 All operations that do not require applications of \mathcal{A} to vectors are polylog linear (i.e.,
 627 $O(N \log(N)^b)$ for some b), and therefore scalable, in the size of the problem, N . We
 628 now describe these costs in detail. For convenience, Table 1 lists variable symbols and
 629 their approximate sizes.

630 (1) *Computing impulse response moments and batches.* Computing V , μ , and Σ
 631 requires applying \mathcal{A}^T to 1, d , and $d(d+1)/2$ vectors, respectively. This works out to
 632 3 applications of \mathcal{A}^T in one spatial dimension, 6 in two dimensions, and 10 in three
 633 dimensions. Computing each η_i requires applying \mathcal{A} to one vector, so computing
 634 $\{\eta_i\}_{i=1}^{n_b}$ requires n_b operator applications. In total, computing all impulse response
 635 moments and batches therefore requires

$$636 \quad 1 + d + d(d+1)/2 + n_b \quad \text{operator applications.}$$

637 In a typical application one might have $d = 2$ and $n_b = 5$, in which case a modest 11
 638 operator applications are required.

639 Computing the impulse response batches also requires choosing sample point
 640 batches via the greedy ellipsoid packing algorithm described in Section 5.1. Choosing
 641 the i th batch of sample points may require performing up to $N|S_i|$ ellipsoid intersec-

642 tion tests, where $|S_i|$ is the number of sample points in the i th batch. Choosing all
 643 of the sample points therefore requires performing at most

644 Nm ellipsoid intersection tests,

645 where m is the total number of sample points in all batches. The multiplicative
 646 dependence of N with m is undesirable since m may be large, and reducing this cost
 647 is possible with more involved computational geometry methods. However, from a
 648 practical perspective, the cost of choosing sample points is small compared to other
 649 parts of the algorithm, and hence such improvements are not pursued here.

650 (2) *Building the H-matrix.* Classical H-matrix construction techniques require
 651 evaluating $O(k_h N \log N)$ matrix entries of the approximation [10], where k_h is the H-
 652 matrix rank, i.e. the maximum rank among the blocks of the H-matrix. To evaluate
 653 one matrix entry, first one must find the k_n nearest sample points to a given point,
 654 where k_n is the number of impulse responses used in the RBF interpolation. This is
 655 done using a precomputed kd-tree of sample points, and requires $O(k_n \log m)$ floating
 656 point and logical elementary operations. Second, one must find the mesh cells that
 657 the points $\{z_i\}_{i=1}^{k_n}$ reside in. This is done using an AABB tree of mesh cells, and
 658 requires $O(k_n \log N)$ elementary operations. Third, one must evaluate finite element
 659 basis functions on those cells, which requires $O(k_n)$ elementary operations. Finally,
 660 the radial basis function interpolation requires solving a $k_n \times k_n$ linear system, which
 661 requires $O(k_n^3)$ elementary operations. Therefore, building the H-matrix requires

662 $O((k_h N \log N)(k_n \log N + k_n^3))$ elementary operations.

663 (3) *Performing linear algebra operations with the H-matrix.* It is well known that
 664 H-matrix methods for matrix-vector products, matrix-matrix addition, matrix-matrix
 665 multiplication, matrix factorization, matrix inversion, and low rank updates require
 666 performing $O(k_h^a N \log(N)^b)$ elementary operations, where $a, b \in \{0, 1, 2, 3\}$ are con-
 667 stants which depend on the type of H-matrix used and the operation being per-
 668 formed [40][52, Section 2.1]. For our numerical results involving Hessians (Sections 7.1
 669 and 7.2), we use one matrix-matrix addition to add the H-matrix approximation of
 670 the data misfit term in the Hessian to the regularization term in the Hessian. Sym-
 671 metrizing \mathbf{A}_H requires one matrix-matrix addition. Flipping negative eigenvalues to
 672 be positive requires a handful (typically around 5) of matrix-matrix additions and
 673 matrix factorizations to factor the required shifted linear systems, and a number of
 674 factorized solves that is proportional to the number of erroneous negative eigenvalues.

675 In summary, computing all the necessary ingredients to evaluate kernel entries of
 676 the PSF-based approximation requires a handful of operator applications (e.g., $6 + n_b$
 677 operator applications in two dimensions, or $10 + n_b$ operator applications in three
 678 dimensions, with n_b typically in the range 1–25), plus comparatively cheap additional
 679 overhead costs, most notably performing ellipsoid intersection tests while choosing
 680 sample point batches. Once these ingredients are computed, no more operator appli-
 681 cations (and thus PDE solves) are required, and approximate kernel entries can be
 682 evaluated rapidly. Constructing the H-matrix from kernel entries requires a number
 683 of elementary operations that scales polylog linearly in N . Using the H-matrix to
 684 perform linear algebra operations also scales polylog linearly in N , though the details
 685 of these costs depend heavily on the type of H-matrix and operation being performed.

686 **7. Numerical results.** We use the PSF-based method to approximate the New-
 687 ton (or Gauss-Newton) Hessians in inverse problems governed by PDEs which model

688 steady state ice sheet flow [64] (Section 7.1) and advective-diffusive transport of a
 689 contaminant [63] (Section 7.2), and to approximate the integral kernel in a blur prob-
 690 lem that is not based on PDEs (Section 7.3). These problems are described in detail
 691 in their respective sections.

692 In both PDE-based inverse problems (Sections 7.1 and 7.2), to reconstruct the
 693 unknown parameter fields, denoted q , the inverse problems are formulated as nonlinear
 694 least squares optimization problems, whose objective functions consist of a data misfit
 695 term (between the observations and model output) and a bi-Laplacian regularization
 696 term following [75]. The regularization is centered at a constant function $q_0(x)$. To
 697 mitigate boundary effects we use a constant coefficient Robin boundary condition as
 698 in [65]. The parameters for the bi-Laplacian operator are chosen so that the Green's
 699 function of the Hessian of the regularization has a characteristic length of 0.25 of the
 700 domain radius. For the specific setup, we refer the reader to [75, Section 2.2]. In all
 701 numerical results we choose the regularization parameter (which controls the overall
 702 strength of the regularization) using the Morozov discrepancy principle [76].

703 We solve the ice sheet inverse problem with an inexact Newton preconditioned
 704 conjugate gradient (PCG) scheme and a globalizing Armijo line search [61]. The
 705 Newton search directions, $\hat{\mathbf{q}}$, are obtained by solving

$$706 \quad (7.1) \quad \mathbf{H}\hat{\mathbf{q}} = -\mathbf{g} \quad \text{or} \quad \mathbf{H}_{\text{gn}}\hat{\mathbf{q}} = -\mathbf{g},$$

707 wherein we choose the initial guess as the discretization of the constant function q_0 .
 708 Here, \mathbf{g} , \mathbf{H} and \mathbf{H}_{gn} are the discretized gradient, Hessian, and Gauss-Newton Hes-
 709 sian of the inverse problem objective function, respectively, evaluated at the current
 710 Newton iterate. To ensure positive definiteness of the Hessian we use \mathbf{H}_{gn} for the
 711 first five iterations, and \mathbf{H} for all subsequent iterations. The Newton iterations are
 712 terminated when $\|\mathbf{g}\| < 10^{-6}\|\mathbf{g}_0\|$, where \mathbf{g}_0 is the gradient evaluated at the initial
 713 guess. Systems (7.1) are solved inexactly using an inner PCG iteration, which is ter-
 714 minated early based on the Eisenstat-Walker [24] and Steihaug [69] conditions. The
 715 inverse problem governed by the advection-diffusion PDE is linear, hence Newton's
 716 method converges in one iteration. In this case the Newton linear system, (7.1), is
 717 solved using PCG, using termination tolerances described in Section 7.2.

718 We use the framework described in this paper to generate Hessian preconditioners.
 719 We build H-matrix approximations, \mathbf{A}_H , of the data misfit Gauss-Newton Hessian
 720 (the term in \mathbf{H}_{gn} that arises from the data misfit). The approximations are indicated
 721 by "PSF (n_b)", where n_b is the number of impulse response batches used to build the
 722 approximation. The Hessian of the regularization term is a combination of stiffness
 723 and mass matrices, which are sparse. Therefore, we form H-matrix representations
 724 of these matrices and combine them into an H-matrix approximation of the regular-
 725 ization term in the Hessian, \mathbf{R}_H , using standard sparse H-matrix techniques. Then,
 726 H-matrix approximations of the Gauss-Newton Hessian, $\mathbf{H}_{\text{gn}} \approx \tilde{\mathbf{H}} := \mathbf{A}_H + \mathbf{R}_H$,
 727 are formed by adding \mathbf{A}_H to \mathbf{R}_H using fast H-matrix arithmetic. We modify $\tilde{\mathbf{H}}$ to
 728 be (approximately) symmetric positive semi-definite via the procedure described in
 729 Section 5.5. We factor $\tilde{\mathbf{H}}$ using fast H-matrix methods, then use the factorization
 730 as a preconditioner. We approximate \mathbf{H}_{gn} rather than \mathbf{H} because \mathbf{H} more often has
 731 negative values in its integral kernel. The numerical results show that $\tilde{\mathbf{H}}$ is a good
 732 preconditioner for both \mathbf{H}_{gn} and \mathbf{H} .

733 **7.1. Example 1: Inversion for the basal friction coefficient in an ice
 734 sheet flow problem.** For this example, we consider a sheet of ice flowing down a
 735 mountain (see Figure 8a). Given observations of the tangential component of the ice

velocity on the top surface of the ice, we invert for the logarithm of the unknown spatially varying basal friction Robin coefficient field, which governs the resistance to sliding along the base of the ice sheet. The setup, which we briefly summarize, follows [48, 64]. The region of ice is denoted by $\mathcal{D} \subset \mathbb{R}^3$. The basal, lateral and top parts of the boundary $\partial\mathcal{D}$ are denoted by Γ_b , Γ_l , and Γ_t , respectively. The governing equations are the linear incompressible Stokes equations,

$$(7.2a) \quad -\nabla \cdot \sigma(v, p) = f \text{ and } \nabla \cdot v = 0 \quad \text{in } \mathcal{D},$$

$$(7.2b) \quad \sigma(v, p)\nu = 0 \quad \text{on } \Gamma_t,$$

$$(7.2c) \quad v \cdot \nu = 0 \text{ and } T(\sigma(v, p)\nu + \exp(q)v) = 0 \quad \text{on } \Gamma_b,$$

$$(7.2d) \quad \sigma(v, p)\nu + sv = 0 \quad \text{on } \Gamma_l.$$

The solution to these equations is the pair (v, p) , where v is the ice flow velocity field⁶ and p is the pressure field. Here, q is the unknown logarithmic basal friction field (large q corresponds to large resistance to sliding) defined on the surface Γ_b . The quantity f is the body force density due to gravity, $s = 10^6$ is a Robin boundary condition constant, ν is the outward unit normal and T is the tangential projection operator that restricts a vector field to its tangential component along the boundary. We employ a Newtonian constitutive law, $\sigma(v, p) = 2\eta\dot{\varepsilon}(v) - Ip$, where σ is the stress tensor and $\dot{\varepsilon}(v) = \frac{1}{2}(\nabla v + \nabla v^\top)$ is the strain rate tensor [48]. Here, η is the viscosity and I is the identity operator. Note that while the PDE is linear, the parameter-to-solution map, $q \mapsto (v, p)$, is nonlinear.

The pressure, p , is discretized with first order scalar continuous Galerkin finite elements defined on a mesh of tetrahedra. The velocity, v , is discretized with second order continuous Galerkin finite elements on the same mesh. The parameter q is discretized with first order scalar continuous Galerkin finite elements on the mesh of triangles that results from restricting the tetrahedral mesh to the basal boundary, Γ_b . Note that Γ_b is a two-dimensional surface embedded in three dimensions due to the mountain topography. The PSF-based method involves translating impulse responses. Hence it requires either a flat domain, or a notion of local parallel transport. We therefore generate a flattened version of Γ_b , denoted by $\Omega \subset \mathbb{R}^2$, by ignoring the height coordinate. The parameter q is viewed as a function on Γ_b for the purpose of solving the Stokes equations, and as a function on Ω for the purpose of building Hessian approximations and defining the regularization. The observations are generated by adding multiplicative Gaussian noise to the tangential component of the velocity field restricted to the top surface of the geometry. We use 5% noise in all cases, except for Figure 9 and Table 3 where the noise is varied from 1% to 25% and the regularization is determined by the Morozov discrepancy principle for each noise level. The true basal friction coefficient and resulting velocity fields, which are obtained by solving (7.2), are shown in Figure 8.

Table 2 shows the performance of the preconditioner for accelerating the solution of the optimization problem to reconstruct \mathbf{q} from observations with 5% noise. We build the PSF (5) preconditioner in the third Gauss-Newton iteration, and reuse it for all subsequent Gauss-Newton and Newton iterations. No preconditioning is used in the iterations before the PSF (5) preconditioner is built. We compare the PSF-based method with the most commonly used existing preconditioners: no preconditioning (NONE), and preconditioning by the regularization term in the Hessian (REG). The

⁶We do not use bold to denote vector or tensor fields to avoid confusion with vectors that arise from finite element discretizations, which are already denoted with bold.

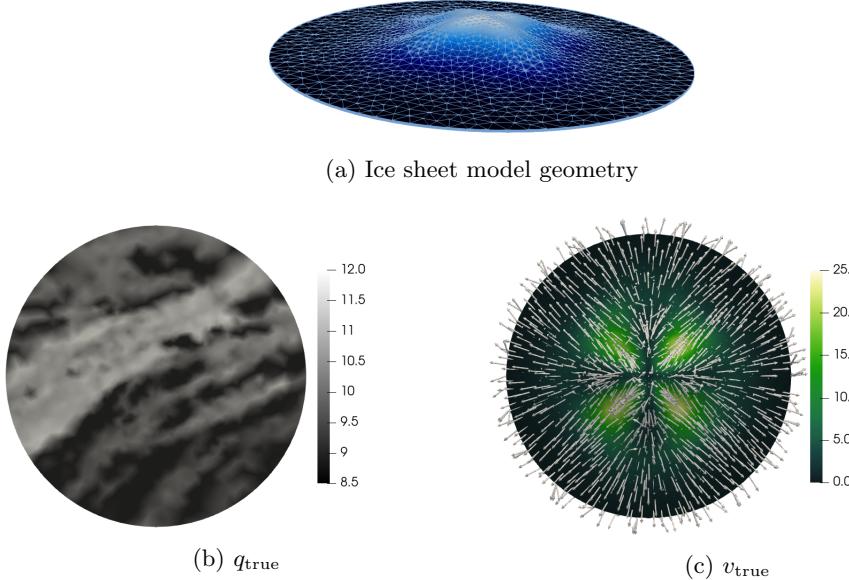


Fig. 8: (Ice sheet) (8a) Bird's eye view of the ice sheet discretized by a mesh of tetrahedra. Color indicates the height of the base of the ice sheet (i.e., the mountain topography). The radius of the domain is 10^4 meters, the maximum height of the mountain is 2.1×10^3 meters, and the average thickness of the ice sheet is 250 meters. (8b) True parameter, q_{true} . (8c) True velocity, v_{true} . Arrows indicate the direction of v_{true} and color indicates the magnitude of v_{true} .



Fig. 9: (Ice sheet) The log basal friction parameter, with color scale as in Figure 8b, computed from the PDE constrained optimization problem with noise levels: 25% (left), 5.0% (middle), and 1.0% (right).

782 results show that using PSF (5) reduces the total number of Stokes PDE solves to 70,
 783 as compared to 908 for regularization preconditioning and 308 for no preconditioning,
 784 a reduction in cost of roughly $5 \times$ – $10 \times$. For problems with a larger physical domain
 785 and correspondingly more observations, such as continental scale ice sheet inversion,
 786 the speedup will be even greater. This is because the rank of the data misfit Hessian
 787 will increase, while the locality of the impulse responses will remain the same. In
 788 Figure 9 we show reconstructions for 1%, 5%, and 25% noise.

Iter	PSF (5)			REG			NONE		
	#CG	#Stokes	$\ \mathbf{g}\ $	#CG	#Stokes	$\ \mathbf{g}\ $	#CG	#Stokes	$\ \mathbf{g}\ $
0	1	4	1.9e+7	3	8	1.9e+7	1	4	1.9e+7
1	2	6	6.1e+6	8	18	8.4e+6	2	6	6.1e+6
2	4	10	2.6e+6	16	34	4.1e+6	4	10	2.6e+6
3	2	6+22	6.9e+5	34	70	1.8e+6	14	30	6.9e+5
4	3	8	4.4e+4	52	106	5.6e+5	29	60	1.3e+5
5	5	12	2.2e+3	79	160	9.4e+4	38	78	1.0e+4
6	0	2	1.1e+1	102	206	6.5e+3	58	118	1.8e+2
7	—	—	—	151	304	1.2e+2	0	2	5.5e-1
8	—	—	—	0	2	2.9e-1	—	—	—
Total	17	70	—	445	908	—	146	308	—

Table 2: (Ice sheet) Convergence history for solving the Stokes inverse problem using inexact Newton PCG to tolerance 10^{-6} . Preconditioners shown are the PSF-based method with five batches (PSF (5)) constructed at the third iteration, regularization preconditioning (REG), and no preconditioning (NONE). Columns #CG show the number of PCG iterations used to solve the Newton system for $\hat{\mathbf{q}}$. Columns $\|\mathbf{g}\|$ show the l^2 norm of the gradient at \mathbf{q} . Columns #Stokes show the total number of Stokes PDE solves performed in each Newton iteration. Under PSF (5) and in row Iter 3, we write 6 + 22 to indicate that 6 Stokes solves were used during the standard course of the iteration, and 22 Stokes solves were used to build the PSF (5) preconditioner.

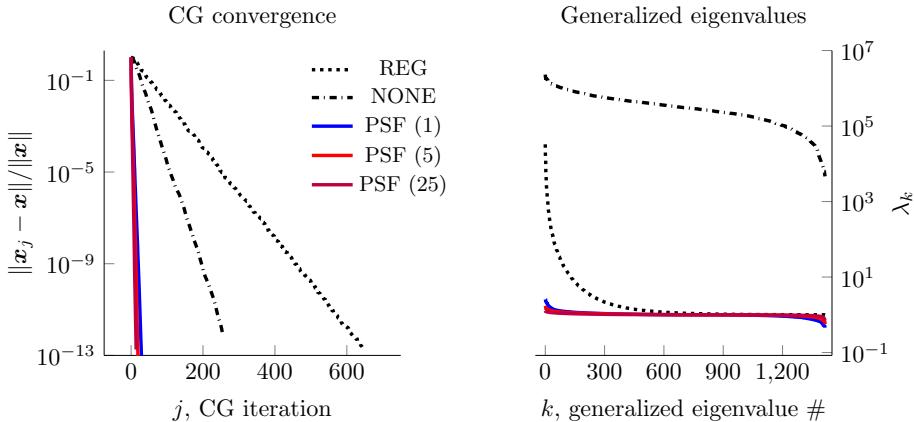


Fig. 10: (Ice sheet) Left: Convergence history for solving $\mathbf{Hx} = \mathbf{b}$ using PCG, where \mathbf{b} has i.i.d. random entries drawn from the standard Gaussian distribution and \mathbf{H} is evaluated at the solution of the inverse problem. Results in these figures are shown for the PSF-based preconditioners with 1, 5, and 25 batches (PSF (1), PSF (5), and PSF (25), respectively), regularization preconditioning (REG), and no preconditioning (NONE). The preconditioner is constructed using \mathbf{H}_{gn} . Right: Generalized eigenvalues for generalized eigenvalue problem $\mathbf{Hu}_k = \lambda_k \tilde{\mathbf{H}}\mathbf{u}_k$. Here, \mathbf{H} is the Hessian and the matrices $\tilde{\mathbf{H}}$ are the same Hessian approximations used in the left sub-figure, with NONE corresponding to the identity matrix.

noise level	COND($\tilde{\mathbf{H}}^{-1}\mathbf{H}$)				
	REG	NONE	PSF (1)	PSF (5)	PSF (25)
25%	1.01e+3	2.96e+3	1.34e+0	1.30e+0	1.18e+0
11%	7.40e+3	1.05e+3	2.27e+0	1.55e+0	1.31e+0
5.0%	3.29e+4	4.96e+2	5.61e+0	3.06e+0	1.92e+0
2.2%	1.66e+5	8.89e+2	1.58e+1	8.07e+0	4.03e+0
1.0%	5.36e+5	1.61e+3	7.17e+1	1.93e+1	9.19e+0

Table 3: (Ice sheet) Condition number for $\tilde{\mathbf{H}}^{-1}\mathbf{H}$ for the PSF-based preconditioners with 1, 5, and 25 batches (PSF (1), PSF (5), and PSF (25), respectively), no preconditioner (NONE) and regularization preconditioning (REG). All operators are evaluated at the soutions of the inverse problems for their respective noise levels.

789 Next, we build PSF (1), PSF (5), and PSF (25) preconditioners based on the
 790 Gauss-Newton Hessian evaluated at the converged solution \mathbf{q} (note: k in PSF (k)
 791 refers to the number of batches; this is not to be confused with the noise levels which
 792 range over the same numerical values). We use PCG to solve a linear system with the
 793 Hessian as the coefficient operator and a right hand side vector with random inde-
 794 pendent and identically distributed (i.i.d.) entries drawn from the standard Gaussian
 795 distribution. In Figure 10 (left) we compare the convergence of PCG for solving this
 796 linear system using the PSF (1), PSF (5), PSF (25), REG, and NONE preconditioners.
 797 PCG converges fastest with the PSF-based preconditioners, with PSF (25) converging
 798 fastest, followed by PSF (5), followed by PSF (1), as expected. In Figure 10 (right) we
 799 show the generalized eigenvalues for the generalized eigenvalue problem $\mathbf{H}\mathbf{u} = \lambda\tilde{\mathbf{H}}\mathbf{u}$.
 800 The matrix $\tilde{\mathbf{H}}$ is one of the PSF (1), PSF (5), or PSF (25) Gauss-Newton Hessian
 801 approximations, the regularization Hessian (REG), or the identity matrix (NONE).
 802 With the PSF-based preconditioners, the generalized eigenvalues cluster near one,
 803 with more batches yielding better clustering.

804 In Table 3, we show the condition number of the preconditioned Hessian for noise
 805 levels ranging from 1% to 25%. Note that the condition number using PSF-based
 806 preconditioners is extremely small (ranging between 1 and 10) and relatively stable
 807 over this range of noise levels. As expected, PSF (25) outperforms PSF (5), which
 808 outperforms PSF (1). All PSF-based preconditioners outperform regularization and
 809 no preconditioning by several orders of magnitude for all noise levels.

810 **7.2. Example 2: Inversion for the initial condition in an advective-
 811 diffusive transport problem.** Here, we consider a time-dependent advection-diffusion
 812 equation in which we seek to infer the unknown spatially varying initial condition,
 813 q , from noisy observation of the full state at a final time, T . This PDE models
 814 advective-diffusive transport in a domain $\Omega \subset \mathbb{R}^d$, which is depicted in Figure 11. In
 815 this case, the state, $c(x, t)$, could be interpreted as the concentration of a contami-
 816 nant. The problem description below closely follows [63, 75]. The domain boundaries
 817 $\partial\Omega$ include the outer boundaries as well as the internal boundaries of the rectangles,
 818 which represent buildings. The parameter-to-observable map \mathcal{F} in this case maps an
 819 initial condition $q \in L^2(\Omega)$ to the concentration field at a final time, $c(x, T)$, through

820 solution of the advection-diffusion equation given by

$$\begin{aligned}
 c_t - \kappa \Delta c + v \cdot \nabla c &= 0 && \text{in } \Omega \times (0, T), \\
 821 \quad (7.3) \qquad c(\cdot, 0) &= q && \text{in } \Omega, \\
 \kappa \nabla c \cdot \nu &= 0 && \text{on } \partial\Omega \times (0, T).
 \end{aligned}$$

822 Here, $\kappa > 0$ is a diffusivity coefficient, ν is the boundary unit normal vector, and $T > 0$
 823 is the final time. The velocity field, $v : \Omega \rightarrow \mathbb{R}^d$, is computed by solving the steady-
 824 state Navier-Stokes equations for a two dimensional flow with Reynolds number 50,
 825 with boundary conditions $v(x) = (0, 1)$ on the left boundary, $v(x) = (0, -1)$ on the
 826 right boundary, and $v(x) = (0, 0)$ on the top and bottom boundaries, as in [63, Section
 827 3]. We use a checkerboard image for the initial condition (Figure 11a) and add 5%
 828 multiplicative noise to generate a synthetic observation at the final time, T . The
 829 initial condition, velocity field, noisy observations, and reconstructed initial condition
 830 are shown in Figure 11. We use $\kappa = 3.2e-1$ and $T = 1.0$ for all results, except for
 831 Table 4 and Figure 12 where we vary κ and T .

832 In Table 4 we show the number of PCG iterations, j , required to solve the Newton
 833 linear system to a relative error tolerance of $\|\hat{\mathbf{q}} - \hat{\mathbf{q}}_j\| < 10^{-6}\|\hat{\mathbf{q}}\|$. The solution of
 834 the Newton system to which we compare, $\hat{\mathbf{q}}$, is found via another PCG iteration with
 835 a relative residual tolerance of 10^{-11} . We show results for T ranging from 0.5 to 2.0
 836 and κ ranging from 10^{-4} to 10^{-3} using the PSF-based preconditioners with 1, 5, and
 837 25 batches, regularization preconditioning, and no preconditioning. The results show
 838 that PSF-based preconditioning outperforms regularization preconditioning and no
 839 preconditioning in all cases except one. The exception is $T = 2.0$ and $\kappa = 1.0e-3$,
 840 in which PSF (1) performs slightly worse than regularization preconditioning but
 841 better than no preconditioning. Adding more batches yields better results, and the
 842 impact of adding more batches is more pronounced here than in the ice sheet example.
 843 For example, in the mid-range values $T = 1.0$ and $\kappa = 3.2e-4$, PSF (1), PSF (5),
 844 and PSF (25) require $1.3\times$, $2.3\times$, and $5.1\times$ fewer PCG iterations, respectively, as
 845 compared to no preconditioning, and exhibit greater improvements as compared to
 846 regularization preconditioning. The PSF preconditioners perform best in the high
 847 rank regime where T is small, which makes sense given that short simulation times
 848 yield more localized impulse responses (see Figure 4). For example, for $\kappa = 3.2e-4$
 849 using the PSF (5) preconditioner yields 140, 202, and 379 iterations for $T = 0.5$,
 850 1.0, and 2.0, respectively. The performance of the PSF preconditioners as a function
 851 of κ does not have as clear of a trend. Reducing κ makes the impulse responses
 852 thinner and hence easier to fit in batches, but also increases the complexity of the
 853 impulse response shapes, which may reduce the accuracy of the RBF interpolation.
 854 The greatest improvements are seen for $T = 0.5$ and $\kappa = 1e-3$, for which PSF (25)
 855 requires roughly $10\times$ and $20\times$ fewer PCG iterations than no preconditioning and
 856 regularization preconditioning, respectively.

857 In Figure 13 (left) we show the convergence of PCG for solving $\mathbf{Hx} = \mathbf{b}$, where
 858 \mathbf{b} has i.i.d. random entries drawn from a standard Gaussian distribution. The pre-
 859 conditioners used, $\tilde{\mathbf{H}}$, are the PSF-based preconditioners with 1, 5, or 25 batches,
 860 the regularization Hessian, and the identity matrix (i.e., no preconditioning). The re-
 861 sults show that PCG converges fastest with the PSF-based preconditioners, with more
 862 batches yielding faster convergence. In Figure 13 (right), we show the eigenvalues for
 863 the generalized eigenvalue problem $\mathbf{Hu} = \lambda \tilde{\mathbf{H}}\mathbf{u}$, where the $\tilde{\mathbf{H}}$ are the preconditioners
 864 stated above. With the PSF-based preconditioners the eigenvalues cluster near one,
 865 and more batches yields better clustering. With the regularization preconditioner the

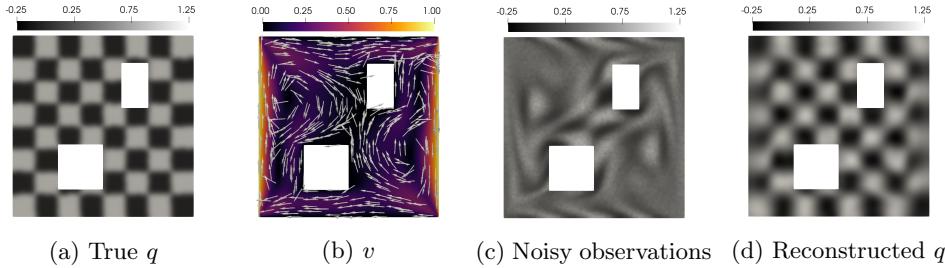


Fig. 11: (Advection-diffusive transport) (11a) True initial condition. (11b) Velocity field. Color indicates magnitude of velocity vector. (11c) Noisy observations of concentration at the final time. (11d) Reconstructed initial condition.

	κ	REG	NONE	PSF (1)	PSF (5)	PSF (25)
$T = 0.5$	1.0e-4	584	317	311	151	56
	3.2e-4	685	311	233	140	44
	1.0e-3	702	324	122	71	33
$T = 1.0$	1.0e-4	634	449	539	288	100
	3.2e-4	681	459	350	202	90
	1.0e-3	574	520	266	260	208
$T = 2.0$	1.0e-4	609	591	548	520	165
	3.2e-4	524	645	318	379	170
	1.0e-3	349	786	381	262	158

Table 4: (Advection-diffusive transport) Number of PCG iterations required to solve the Newton linear system to tolerance $\|\hat{\mathbf{q}}_j - \hat{\mathbf{q}}\| < 10^{-6}\|\hat{\mathbf{q}}\|$, where $\hat{\mathbf{q}}_j$ is the j th iterate, and $\hat{\mathbf{q}}$ is the solution of the Newton linear system. Iteration counts are shown for a variety of different diffusion parameters κ , simulation times T , and preconditioners.

866 trailing eigenvalues cluster near one, while the leading eigenvalues are amplified.

867 **7.3. Example 3: Spatially varying blurring problem.** Here, we define a
868 PDE-free spatially varying blur problem, in which the impulse response, ϕ_x , is a
869 bumpy blob that is centered near x , and is rotated and scaled in a manner that
870 depends on x (see Figure 2). This blur problem is used in Sections 1 and 3 to visually
871 illustrate various stages and aspects of the PSF-based method, and robustness (or lack
872 thereof) of the PSF-based method to violations of the non-negative kernel assumption
873 (Section 3.2). In this section, the blur problem is used to compare the PSF-based
874 method to hierarchical off-diagonal low rank (HODLR) and global low rank (GLR)
875 methods, to study convergence of the PSF-based method, and to investigate the effect
876 of the ellipsoid size parameter τ . The closed form expression for the integral kernel is
877 given by

878 (7.4)
$$\Phi(y, x) = (1 - af(y, x))g(x) \exp\left(-\frac{1}{2}(h(y, x)^T C^{-1} h(y, x)\right),$$

879

880 where $f(y, x) = \cos(h^1(y, x)/\sqrt{c_1/2}) \sin(h^2(y, x)/\sqrt{c_2/2})$, with $h^i(y, x)$ the i^{th}
881 component of $R(\theta(x))(y - x)$, with $R(\theta(x))$ a two-dimensional rotation matrix by

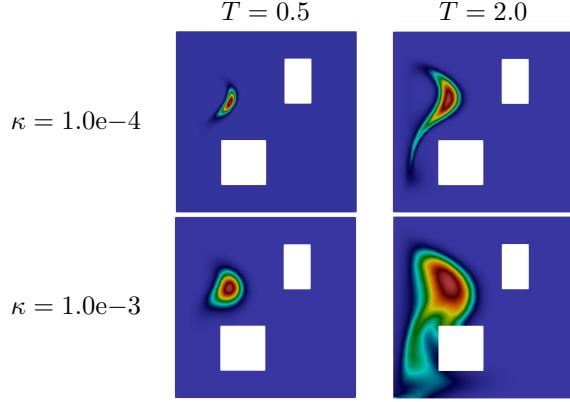


Fig. 12: (Advection-diffusive transport) Impulse responses for small and large diffusion parameters κ and simulation times T .

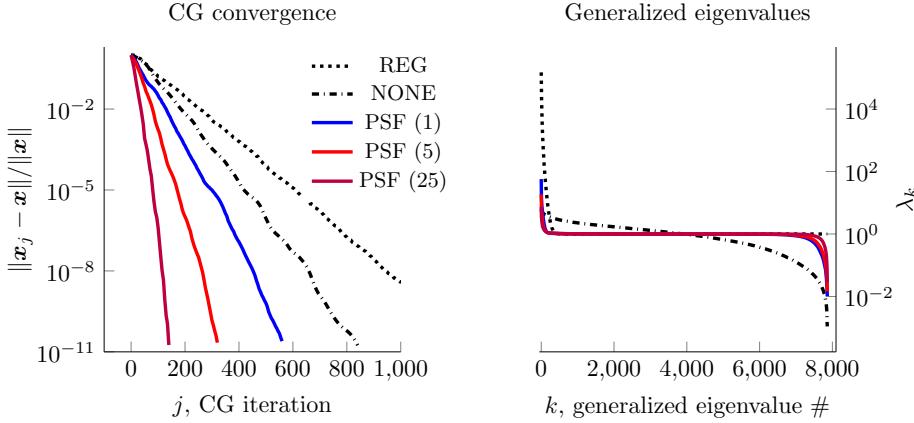


Fig. 13: (Advection-diffusive transport) Left: Convergence history for solving $\mathbf{H}\mathbf{x} = \mathbf{b}$ using PCG, where \mathbf{b} has i.i.d. random entries drawn from the standard Gaussian distribution. Right: Generalized eigenvalues for generalized eigenvalue problem $\mathbf{H}\mathbf{u}_k = \lambda_k \tilde{\mathbf{H}}\mathbf{u}_k$. Here, \mathbf{H} is the Hessian and the preconditioner, $\tilde{\mathbf{H}}$, is the PSF-based approximation for 1, 5, or 25 batches (PSF (1), PSF (5), and PSF (25), respectively), the regularization Hessian (REG), or the identity matrix (NONE).

angle $\theta(x) = (x^1 + x^2)\pi/2$, $g(x) = x^1(1 - x^1)x^2(1 - x^2)$, and with $C = L^2 \text{diag}(c_1, c_2)$. The constant L controls the width of the blob, and c_1/c_2 controls its aspect ratio. The constant a represents deviation from a Gaussian. When $a = 0$, ϕ_x is a Gaussian, and as a increases, ϕ_x becomes non-Gaussian. When $a > 1$, the integral kernel contains negative values, which allows us to study the robustness of the PSF-based method to violations of Assumption 3 (Section 3.2).

In Table 5 we compare the cost to approximate the blur kernel from Equation (7.4) using the PSF-based method, the randomized HODLR (hierarchical off diagonal low rank) method [58, 45] with 8 levels, and GLR (global low rank) approximation using

	Error tol.	#applies PSF	#applies HODLR	#applies RSVD
$L = 1$	20%	11	592	354
	10%	16	772	520
	5%	22	924	674
$L = 1/2$	20%	8	852	1316
	10%	9	1144	1916
	5%	12	1404	2456
$L = 1/3$	20%	7	932	2624
	10%	8	1264	3734
	5%	8	1520	4660

Table 5: (Blur) Comparison of cost to approximate the blur kernel from Equation (7.4) using the PSF-based method, the randomized HODLR (hierarchical off diagonal low rank) method, and GLR (global low rank) approximation using randomized SVD. The quantity L scales the width of the impulse responses, hence it influences the rank of the operator. Large L means low rank, and small L means high rank. The second column (“Error tol”) is the relative error in the approximation of the kernel measured in the Frobenius norm, $\|\Phi - \tilde{\Phi}\|_{\text{Fro}}/\|\Phi\|_{\text{Fro}}$. The remaining three columns show the number of operator applies required to achieve the given error tolerances, using the PSF, HODLR, and GLR methods.

double-pass randomized SVD [44]. For these results we vary the quantity L to scale the width of the impulse responses and hence the rank of the operator. For each case, we calculate the relative error in the approximation of the kernel measured in the Frobenius norm, $\|\Phi - \tilde{\Phi}\|_{\text{Fro}}/\|\Phi\|_{\text{Fro}}$ and show the number of operator applications required to achieve 20%, 10%, and 5% relative error by each method. The results reveal superior performance of the PSF method as compared to the HODLR and GLR methods for all cases. We note that as we increase the rank and decrease the error tolerance, the performance of the HODLR and GLR methods deteriorates.

In Figure 14 we show the convergence of the PSF-based method on the blur kernel as a function of the total number of impulse responses (left), and the number of batches (right). We show convergence for several ellipsoid size parameters τ , ranging from 2.0–4.0. The results in Figure 14 (left) show that the relative error decreases as constant \times (#impulse responses) $^{-1}$ suggesting linear convergence. The linear convergence stalls at a limit that depends on τ . Increasing τ lowers this limit, allowing the PSF-based method to achieve higher accuracy. In Figure 14 (right), the results show that before this limit is reached, the convergence is faster for smaller τ in terms of the number of batches. This is expected because smaller τ results in more impulse responses per batch. Larger τ causes the PSF-based method to converge more slowly than smaller τ , but with larger τ the PSF-based method stalls at a lower level of error than it does with smaller τ (see, e.g., $\tau = 4.0$ vs. $\tau = 2.5$).

8. Conclusions. We presented an efficient matrix-free PSF-based method for approximating operators with locally supported non-negative integral kernels. The PSF-based method requires access to the operator only via application of the operator to a small number of vectors. The idea of the PSF-based method is to compute batches of impulse responses by applying the operator to Dirac combs of scattered point sources, then interpolate these impulse responses to approximate entries of the operator’s integral kernel. The interpolation is based on a new principle we call “local

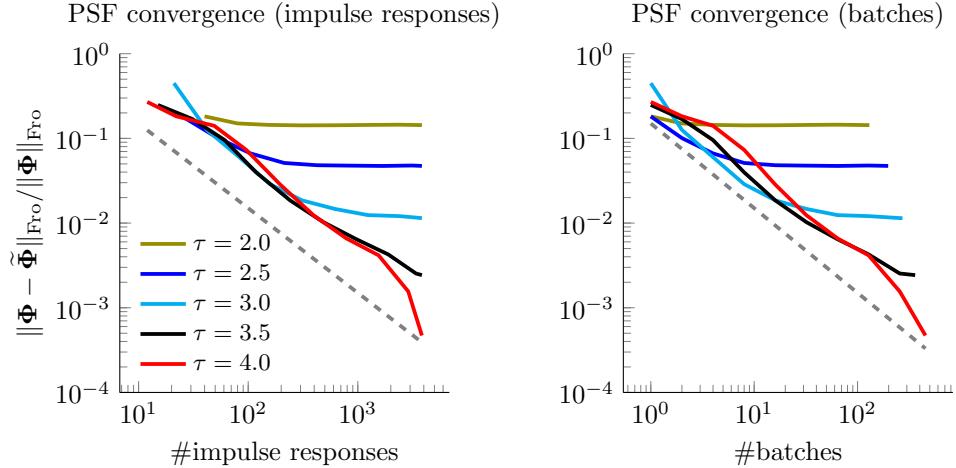


Fig. 14: (Blur) Relative error for different ellipsoid size parameters, τ , vs. the total number of impulse responses (left), and the number of batches (right). The dashed gray lines show linear convergence rates, i.e., constant \times (<#impulse responses>) $^{-1}$ on the left, and constant \times #batches $^{-1}$ on the right.

mean displacement invariance,” which generalizes classical local translation invariance. The ability to quickly approximate arbitrary integral kernel entries permits us to form an H-matrix approximation of the operator. Fast H-matrix arithmetic is then used to perform further linear algebra operations that cannot be performed easily with the original operator, such as matrix factorization and inversion. The supports of the impulse responses are estimated to be contained in ellipsoids, which are determined a-priori via a moment method that involves applying the operator to a small number of polynomial functions. Point source locations for the impulse response batches are chosen using a greedy ellipsoid packing procedure, in which we choose as many impulse responses per batch as possible, while ensuring that the corresponding ellipsoids do not overlap. We applied the PSF-based method to approximate the Gauss-Newton Hessians in an ice sheet flow inverse problem governed by a linear Stokes PDE, and an advective-diffusive transport inverse problem governed by an advection-diffusion PDE. We saw that preconditioners based on the PSF-based approximation cluster the eigenvalues of the preconditioned Hessian near one, and allow us to solve the inverse problems using roughly $5 \times 10 \times$ fewer PDE solves. For larger domains with more observations, the rank of the data misfit Hessian will increase, while the locality of impulse responses will remain the same. Hence, we expect the speedup will be even greater for such problems. Although the PSF-based method is not applicable to all Hessians, it is applicable to many Hessians of practical interest. For these Hessians, the PSF-based method offers a *data scalable* alternative to conventional low rank approximation, due to the ability to form high rank approximations of an operator using a small number of operator applications, and thus PDE solves.

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