CHOOSE AN APPROPRIATE TITLE

by

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Dedication

This thesis is dedicated to those who have fuelled my interest in numerical analysis through their genious, creativity and passion. Include best graphic or logo

Acknowledgments

ToBeDone

Don't forget NSERC+McGill Funding

Abstract

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Contents

List of Figures

List of Tables

Chapter 1

Introduction

1.1 ToBeModified

Chapter 2

Methodology

In this section, the governing equations of fluid mechanics and heat transfer, as well as the associated discretizations and boundary conditions employed are outlined. As this work is concerned with the solution of these equations through variants of the finite element method, we also outline the spaces used for the discretization.

Row-vector notation is assumed throughout with the following notation employed:

Object	Description	Example
Scalar variable	italic	a
Vector variable	italic boldface lowercase	$\boldsymbol{a}$
Second-order tensor variable	italic boldface uppercase	$\boldsymbol{A}$
Vector	boldface lowercase	$\mathbf{a}$
Matrix	boldface uppercase	$\mathbf{A}$
Spaces	calligraphic uppercase	$\mathscr{A}$

2.1 Governing Equations

Following the notation of Pletcher et al. [1, Chapter 5], the continuity, Navier-Stokes and energy equations with source terms neglected are given by

$$\frac{\partial \boldsymbol{w}}{\partial t} + \nabla \cdot \left(\boldsymbol{F}^{\boldsymbol{i}}(\boldsymbol{w}) - \boldsymbol{F}^{\boldsymbol{v}}(\boldsymbol{w}, \boldsymbol{Q}) \right) = \mathbf{0}, \tag{2.1}$$

where the vector of conservative variables and its gradients are defined as

$$\begin{aligned} \boldsymbol{w} &:= \begin{bmatrix} \rho & \rho\boldsymbol{v} & E \end{bmatrix} && \in \mathbb{R}^{d+2} \\ \boldsymbol{Q} &:= \nabla^T \boldsymbol{w} && \in \mathbb{R}^{d+2} \times \mathbb{R}^{d}, \end{aligned} \tag{2.2}$$

where d is the problem dimension, and where the inviscid and viscous fluxes are defined as

$$\boldsymbol{F}^{\boldsymbol{i}}(\boldsymbol{w}) := \begin{bmatrix}\rho\boldsymbol{v}^T & \rho\boldsymbol{v}^T\boldsymbol{v}+p\boldsymbol{I} & (E+p)\boldsymbol{v}^T\end{bmatrix} \in \mathbb{R}^{d+2}\times\mathbb{R}^d, \tag{2.3}$$

$$\boldsymbol{F}^{\boldsymbol{v}}(\boldsymbol{w},\boldsymbol{Q}) := \begin{bmatrix}\boldsymbol{0}^T & \boldsymbol{\Pi} & \boldsymbol{\Pi}\boldsymbol{v}^T-\boldsymbol{q}^T\end{bmatrix} \in \mathbb{R}^{d+2}\times\mathbb{R}^d. \tag{2.4}$$

The various symbols represent the density, ρ, the velocity, $\boldsymbol{v}$, the total energy per unit volume, E, the pressure, p, the stress tensor, $\boldsymbol{\Pi}$ and the energy flux, $\boldsymbol{q}$. The pressure is defined according to the equation of state for a calorically ideal gas,

$$p = (\gamma-1)\left(E-\frac{1}{2}\rho\boldsymbol{v}\boldsymbol{v}^T\right) := (\gamma-1)\rho e,\ \gamma=\frac{c_p}{c_v},\ c_v=\frac{R_g}{\gamma-1},\ c_p=\frac{\gamma R_g}{\gamma-1},$$

where e represents the specific internal energy, R_g is the gas constant and the specific heats at constant volume, c_v, and at constant pressure, c_p, are constant. The stress tensor is defined as

$$\boldsymbol{\Pi} = 2\mu\left(\boldsymbol{D}-\frac{1}{3}\nabla\cdot\boldsymbol{v}\boldsymbol{I}\right),\ \boldsymbol{D} := \frac{1}{2}\left(\nabla^T\boldsymbol{v}+\left(\nabla^T\boldsymbol{v}\right)^T\right),$$

where μ is the coefficient of shear viscosity (Add comment about how μ is determined (Sutherland, p.259 pletcher(1997))) and where the coefficient of bulk viscosity was assumed to be zero. Finally, the energy flux is defined by

$$\boldsymbol{q} = \kappa\nabla T,$$

where T represents the temperature and

$$\kappa = \frac{c_p\mu}{Pr},$$

with Pr representing the Prandtl number. In the case of the Euler equations, the contribution of the viscous flux is neglected.

2.2 Discretizations

2.2.1 Preliminaries

Let Ω be a bounded simply connected open subset of $\mathbb{R}^d$ with connected Lipschitz boundary $\partial\Omega$ in $\mathbb{R}^{d-1}$. We let Ω_h denote the disjoint partion of Ω into "elements", V, and denote the element boundaries as ∂V. Elements and their boundaries are also referred to as volumes and faces respectively. We also define the following volume inner products,

$$
\begin{aligned}
(a, b)_D &= \int_D ab; \qquad a, b \in L^2(D), \\
(\mathbf{a}, \mathbf{b})_D &= \int_D \mathbf{a} \cdot \mathbf{b}; \quad \mathbf{a}, \mathbf{b} \in L^2(D)^m, \\
(\mathbf{A}, \mathbf{B})_D &= \int_D \mathbf{A} : \mathbf{B};\ \mathbf{A}, \mathbf{B} \in L^2(D)^{m\times d},
\end{aligned}
$$

where D is a domain in $\mathbb{R}^d$, and where ':' denotes the inner product operator for two second-order tensors. Analogous notation is used for face inner products,

$$
\begin{aligned}
\langle a, b\rangle_D &= \int_D ab; \qquad a, b \in L^2(D), \\
\langle \mathbf{a}, \mathbf{b}\rangle_D &= \int_D \mathbf{a} \cdot \mathbf{b}; \quad \mathbf{a}, \mathbf{b} \in L^2(D)^m, \\
\langle \mathbf{A}, \mathbf{B}\rangle_D &= \int_D \mathbf{A} : \mathbf{B};\ \mathbf{A}, \mathbf{B} \in L^2(D)^{m\times d},
\end{aligned}
$$

where D is a domain in $\mathbb{R}^{d-1}$. Denoting the polynomial space of order p on domain D as $\mathscr{P}^p(D)$, and letting $n = d + 2$, we define the discontinuous discrete solution and gradient approximation spaces as

$$
\begin{aligned}
\mathcal{S}_h^v &= \{\boldsymbol{a} \in L^2(\Omega_h)^n : \boldsymbol{a}|_V \in \mathscr{P}^p(V)^n\ \forall V \in \Omega_h\} \\
\mathcal{G}_h^v &= \{\boldsymbol{A} \in L^2(\Omega_h)^{n\times d} : \boldsymbol{A}|_V \in \mathscr{P}^p(V)^{n\times d}\ \forall V \in \Omega_h\}.
\end{aligned}
$$

We also define discontinuous test spaces

$$\mathscr{W}_{t\,h}^{\,v} = \{\mathbf{a_t} \in L^2(\Omega_h)^n : \mathbf{a_t}|_V \in \mathscr{P}^{p_t}(V)^n \;\forall V \in \Omega_h\}$$
$$\mathscr{Q}_{t\,h}^{\,v} = \{\mathbf{A_t} \in L^2(\Omega_h)^{n\times d} : \mathbf{A_t}|_V \in \mathscr{P}^{p_t}(V)^{n\times d} \;\forall V \in \Omega_h\},$$

where $p_t \geq p$. Will need additional spaces for DPG.

2.2.2 Discretized Equations

To obtain the discrete formulation, we first define a joint flux $\boldsymbol{F}(\boldsymbol{w},\boldsymbol{Q}) \coloneqq \boldsymbol{F^i}(\boldsymbol{w}) - \boldsymbol{F^v}(\boldsymbol{w},\boldsymbol{Q})$ then integrate (2.2) and (2.1) with respect to test functions to obtain

$$\begin{aligned}
(\mathbf{Q_t},\boldsymbol{Q})_V &= \left(\mathbf{Q_t},\nabla^T\boldsymbol{w}\right)_V, && \forall \mathbf{Q_t} \in \mathscr{Q}_{t\,h}^{\,v} = \mathscr{Q}_h^v\\
\left(\mathbf{w_t},\frac{\partial \boldsymbol{w}}{\partial t}\right)_V &+ (\mathbf{w_t},\nabla\cdot\boldsymbol{F}(\boldsymbol{w},\boldsymbol{Q}))_V = \mathbf{0}, && \forall \mathbf{w_t} \in \mathscr{W}_{t\,h}^{\,v} = \mathscr{W}_h^v.
\end{aligned}$$

Integrating by parts twice in the first equation and once in the second and choosing $p_t = p$, such that the approximation and test spaces are the same, results in the discontinuous Galerkin formulation,

$$\begin{aligned}
(\mathbf{Q_t},\boldsymbol{Q})_V &= \left(\mathbf{Q_t},\nabla^T\boldsymbol{w}\right)_V + \langle\mathbf{Q_t},\mathbf{n}\cdot(\boldsymbol{w}^*-\boldsymbol{w})\rangle_{\partial V}, && \forall \mathbf{Q_t} \in \mathscr{Q}_h^v\\
\left(\mathbf{w_t},\frac{\partial \boldsymbol{w}}{\partial t}\right)_V &- (\mathbf{w_t},\nabla\cdot\boldsymbol{F}(\boldsymbol{w},\boldsymbol{Q}))_V + \langle\mathbf{w_t},\mathbf{n}\cdot\boldsymbol{F}^*\rangle_{\partial V} = \mathbf{0}, && \forall \mathbf{w_t} \in \mathscr{W}_h^v.
\end{aligned}$$

where $\mathbf{n}$ denotes the outward pointing unit normal vector and where $\boldsymbol{w}^*$ and $\boldsymbol{F}^*$ represent the numerical solution and flux respectively.

2.3 Boundary Conditions

Boundary conditions are imposed weakly through the specification of a 'ghost' state for elements in which $V \cap \partial\Omega \neq \{0\}$. The following boundary conditions are supported:

Boundary Condition	Reference(s)	Comments
Riemann Invariant	[2, section 2.2]	eq. (14) should read $c_b = \frac{\gamma-1}{4}(R^+ - R^-)$
Slip-Wall	[3, eq. (10)]	
Back Pressure (Outflow)	[2, section 2.4]	
Total Temperature/Pressure (Inflow)	[2, section 2.7]	
Supersonic Inflow/Outflow		imposes the exact/extrapolated solution
No-slip Overconstrained		imposes values for all primitive variables [1]
No-slip Diabatic		imposes $\mathbf{v}$ and $(\mathbf{n} \cdot \mathbf{F}(\mathbf{W}, \mathbf{Q}))_E = \text{constant}$

[1] Add reference to Nordstrom explaining why this BC is overconstrained and add link to Taylor-Couette results where it is used.

Chapter 3

The DPG Methodology

In comparison to discontinuous Galerkin (DG) methods, the noteworthy characteristic of the Discontinuous Petrov-Galerkin (DPG) methodology is that the optimal (to be defined below) test space is computed based on the minimization of the residual in a specified norm instead of simply being chosen to be the same as the trial space. Following Demkowicz et al. [4], DPG is generally referred to as a methodology, as opposed to a method, as different methods are obtained depending on the choice of inner product in the test space. As it is heavily relied on in the following presentation, it may be assumed that all spaces considered are Hilbert spaces.

3.1 Linear DPG

In this section, we first outline the basic concepts of DPG methods in an abstract linear functional setting and then provide a concrete example through the application of the theory to the linear advection equation.

3.1.1 Abstract Functional Setting

Much of the theory outlined below is borrowed directly from the works of Demkowicz et al. [5, 4]. Of primary note, it is demonstrated that each DPG method can be interpreted as the *localization* of a method achieving optimal discrete stability through the choice of an optimal conforming test space.

A Petrov-Galerkin Variational Methodology with Optimal Stability

Consider the *linear* abstract variational problem

$$\text{Find } u \in U \text{ such that } b(v,u) = l(v)\ \forall v \in V, \tag{3.1}$$

where U and V denote the trial and test spaces, respectively, which are assumed to be Hilbert spaces, and where the bilinear form $b(\cdot,\cdot)$ acting on $V \times U$ and the linear form $l(\cdot)$ acting on V correspond to a particular variational formulation. It is assumed that the bilinear form satisfies a continuity condition with continuity constant M,

$$|b(v,u)| \leq M||v||_V||u||_U, \tag{3.2}$$

and an inf-sup condition with inf-sup constant γ,

$$\exists \gamma > 0 : \inf_{u \in U} \sup_{v \in V} \frac{b(v,u)}{||v||_V||u||_U} \geq \gamma. \tag{3.3}$$

Further, it is assumed that the linear form is continuous and satisfies the following compatibility condition

$$l(v) = 0 \ \forall v \in V_0, \text{ where } V_0 \coloneqq \{v \in V : b(v,u) = 0 \ \forall u \in U\}. \tag{3.4}$$

Then, by the Banach-Nečas-Babuška theorem (Add reference to Brener-Scott/Ciarlet), (3.1) has a unique solution, u, that depends continuously on the data,

$$||u||_U \leq \frac{M}{\gamma}||l||_{V'}, \tag{3.5}$$

where V' denotes the dual space of V. Now let $U_h \subseteq U$ and $V_h \subseteq V$ be finite dimensional trial and test spaces and consider the finite dimensional variation problem

$$\text{Find } u_h \in U_h \text{ such that } b(v_h,u_h) = l(v_h) \ \forall v_h \in V_h. \tag{3.6}$$

If the form satisfies the discrete inf-sup condition with inf-sup constant γ_h,

$$\exists \gamma_h > 0 : \inf_{u_h \in U_h} \sup_{v_h \in V_h} \frac{b(v_h,u_h)}{||v_h||_{V_h}||u_h||_{U_h}} \geq \gamma_h, \tag{3.7}$$

then Babuška's theorem [6, Theorem 2.2] demonstrates that the discrete problem, (3.6), is well-posed with the Galerkin error satisfying the error estimate,

$$||u_h - u||_U \leq \frac{M}{\gamma_h} \inf_{w_h \in U_h} ||w_h - u||_U. \tag{3.8}$$

where the original constant in the bound, $\left(1 + \frac{M}{\gamma_h}\right)$ [6, eq. (2.14)], has been sharpened to $\frac{M}{\gamma_h}$ as demonstrated to be possible by Xu et al. [7, Theorem 2]. Generally, the well-posedness of the continuous problem does not imply the well-posedness of the discrete problem (i.e. (3.3) $\not\Rightarrow$ (3.7)), and the fundamental motivation for the DPG methodology is then to choose the test space such that the supremum in the discrete inf-sup condition, (3.7), is obtained. (Potentially refer to where it is proven that DPG test functions are chosen in this way (following the demonstration in Demkowicz et al. [4, Section 4.1]))

A case of particular interest is then when the continuity and discrete inf-sup constants can be made equal,

$$M = \gamma_h, \tag{3.9}$$

so that the error incurred by the discrete approximation in (3.8) is smallest. As it is not immediately clear which norms should be selected for the trial and test spaces, the simplest strategy is to let the norm be chosen as that which is naturally induced by the problem such that (3.9) is satisfied. Bui-Thanh et al. [8, Theorem 2.6] have proven that $M = \gamma = 1$ if

$$\exists v_u \in V \ \setminus \{0\} : b(v_u, u) = ||v_u||_V ||u||_U \ \forall u \in U \setminus \{0\}, \tag{3.10}$$

where v_u is termed an optimal test function for the trial function u. Further, assuming that (3.10) holds, (3.9) is satisfied when the discrete test space is defined by

$$V \supset V_h = span\{v_{u_h} \in V : u_h \in U_h \subseteq U, \ b(v_{u_h}, u_h) = ||v_{u_h}||_V ||u_h||_U\}; \tag{3.11}$$

see Bui-Thanh et al. [8, Lemma 2.8]. Defining the map from trial to test space, $T : U \ni u \to Tu \coloneqq v_{Tu} \in V$, by

$$(v, Tu)_V = b(v, u), \tag{3.12}$$

where $(\cdot, \cdot)_V$ represents the test space inner product, then the discrete test space, (3.11), is equivalently defined as

$$V_h = span\{v_{Tu_h} \in V : u_h \in U_h\}; \tag{3.13}$$

see Bui-Thanh et al. [8, Theorem 2.9]. Defining the Riesz operator for the test inner product,

$$R_V : V \ni v \to (v, \cdot) \in V', \tag{3.14}$$

which is an isometric isomorphism ([9, Theorem 4.9-4]), the test functions spanning V_h, which are henceforth referred to as *optimal* test functions, can be computed through the inversion of the Riesz operator by solving the auxiliary variational problem

$$\text{Find } v_{Tu_h} \in V \text{ such that } (w, v_{Tu_h})_V = b(w, u_h),\ \forall w \in V. \tag{3.15}$$

DPG as a Localization of the Optimal Conforming PG Methodology

Note that no assumptions regarding the conformity of the trial and test spaces were imposed in §3.1.1. Specifically, the specification of the 'D' (discontinuous) in DPG, referring to a discontinuous test space, has not yet been made and the methodology described is thus of a general Petrov-Galerkin form. Denote the trial *graph* space over the domain Ω, $H_b(\Omega)$, as that of the solution of (3.1),

$$H_b(\Omega) \coloneqq \{u \in (L^2(\Omega))^n : b(v, u) \in (L^2(\Omega))^n \ \forall v \in V\}, \tag{3.16}$$

where n denotes the number of scalar variables. Integration by parts of (3.1) leads to the formal L^2-adjoint and a bilinear form representing the boundary terms

$$b(v,u) = b^*(v,u) + c(\mathrm{tr}_A^* v, \mathrm{tr}_A u) \tag{3.17}$$

where v is in the graph space for the adjoint

$$H_b^*(\Omega) \coloneqq \{v \in (L^2(\Omega))^n : b^*(v,u) \in (L^2(\Omega))^n \ \forall u \in U\}. \tag{3.18}$$

See Demkowicz et al. [5, eq. (4.18)] for a concrete example of these operators. When setting $V = H_b^*(\Omega)$, we say that the test space is H_b-conforming.

As the eventual goal of the methodology is to solve (3.6) over a tessellation, $\mathscr{T}_h$, of the discretized domain, Ω_h, consisting of elements (referred to as volumes) $\mathscr{V}$, we note that using an H_b-conforming test space results in each of the optimal test functions computed by (3.15) having global support (i.e. potentially over all of Ω_h). To make the methodology practical, broken energy spaces are introduced such that the required inversion of the Riesz operator can be done elementwise, *localizing* (3.15),

$$\text{Find } v_{Tu_h} \in V(\mathscr{V}) \text{ such that } (w, v_{Tu_h})_{V(\mathscr{V})} = b(w, u_h),\ \forall w \in V(\mathscr{V}) \tag{3.19}$$

where

$$V(\Omega_h) \coloneqq \{v \in L^2(\Omega) : v|_{\mathscr{V}} \in H_b^*(\mathscr{V}) \ \forall \mathscr{V} \in \mathscr{T}_h\}, \tag{3.20}$$

$$(w,v)_{V(\Omega_h)} \coloneqq \sum_{\mathscr{V}} (w|_{\mathscr{V}}, v|_{\mathscr{V}})_{V(\mathscr{V})} \tag{3.21}$$

and $V(\mathscr{V})$ is the volume test space. Finally, it must be noted that the variational problem for the test functions, (3.19), is infinite dimensional. In practice, it must be solved approximately, for *approximate optimal test functions*, in an approximate volume test space $\tilde{V} \subseteq V$,

$$\text{Find } \tilde{v}_{Tu_h} \in \tilde{V}(\mathscr{V}) \text{ such that } (\tilde{w}, \tilde{v}_{Tu_h})_{\tilde{V}(\mathscr{V})} = b(\tilde{w}, u_h), \ \forall \tilde{w} \in \tilde{V}(\mathscr{V}), \tag{3.22}$$

where the corresponding approximate optimal test space is, analogous to (3.13), defined by

$$\tilde{V}_h = span\{\tilde{v}_{Tu_h} \in \tilde{V} : u_h \in U_h\}. \tag{3.23}$$

Potentially add comment regarding account for the approximation of optimal test functions [5, eqs. (4.30) - (4.32)].

Noting that the test graph space is a subset of $(L^2(\Omega))^n$, it has been shown that the PG methodology of §3.1.1 is, in fact, a subset of this practical DPG methodology where L^2-conforming test spaces are used as shown in the proof of Proposition 3.1.1. This however comes at the cost of introducing trace unknowns over the interior volume boundaries, in addition to the already existing trace unknowns on the domain boundary, both of which are subsequently denoted by $\hat{u}$.

Defining the group variable $\boldsymbol{u} \coloneqq (u, \hat{u})$ containing both the solution components in L^2 as well as those defined on traces (boundary and internal), we separate the bilinear form into the following components

$$b(v, \boldsymbol{u}) \coloneqq b(v, (u, \hat{u})) \coloneqq \bar{b}(v, \boldsymbol{w}) + \langle\langle v, \hat{w} \rangle\rangle \tag{3.24}$$

where $\bar{b}(v, \boldsymbol{w})$ includes all terms present in the PG methodology outlined in §3.1.1 and $\langle\langle v, \hat{w} \rangle\rangle$ accounts for newly introduced terms arising as a result of the usage of the broken tests space. Above, w includes the solution component in L^2, u, as well as the trace component on the domain boundary while $\hat{w}$ includes only the trace component on the internal volume boundaries. Following the previous notation, discrete solution variables are represented by

$\boldsymbol{w}_h \in U_h \times \hat{U}_h$ and $\hat{w}_h \in \hat{W}_h \subset \hat{U}_h$. Defining the weakly conforming optimal test space as

$$\bar{V}_h = \{v \in \tilde{V}_h : \langle\langle v, \hat{w}_h \rangle\rangle = 0 \; \forall \hat{w}_h \in \widetilde{\hat{W}}\}, \tag{3.25}$$

we have the following

Proposition 3.1.1 (PG Test Space as a Strict Subset of DPG Test Space)**.** $\bar{V}_h \subset \tilde{V}_h$.

Proof. We briefly reproduce the proof of Demkowicz et al. [5, Section 6]. As $\tilde{V}$ is a finite dimensional Hilbert space and $\tilde{V}_h \subseteq \tilde{V}$, the direct sum theorem [9, Theorem 4.5-2] allows for its decomposition as

$$\tilde{V} = \tilde{V}_h + \tilde{V}_h^{\perp} \tag{3.26}$$

where $\tilde{V}_h^{\perp}$ is the $\tilde{V}$-orthogonal complement of $\tilde{V}_h$ in $\tilde{V}$. This can be seen from

$$\begin{aligned} \tilde{V}_h^{\perp} &\coloneqq \{\tilde{v} \in \tilde{V} : (\tilde{x}, \tilde{v})_{\tilde{V}(\mathscr{V})} = b(\tilde{x}, \boldsymbol{u}_h), \; \forall \boldsymbol{u}_h \in U \setminus U_h, \; \forall \tilde{x} \in \tilde{V}(\mathscr{V})\} && \text{(using (3.22))} \\ &= \{\tilde{v} \in \tilde{V} : (\tilde{x}, \tilde{v})_{\tilde{V}(\mathscr{V})} = 0, \; \forall \tilde{x} \in \tilde{V}(\mathscr{V})\}. && \text{(by Galerkin orthogonality)} \end{aligned}$$

Think about the implication above that $(\tilde{x}, \tilde{v})_{\tilde{V}(\mathscr{V})} \neq 0 \; \forall \tilde{v} \in \tilde{V}_h, \; \forall \tilde{x} \in \tilde{V}(\mathscr{V})$.

Let $\bar{V}_h \ni \bar{v} = \{v \in \tilde{V} : (\tilde{x}, v)_{\tilde{V}(\mathscr{V})} = \bar{b}(\tilde{x}, \boldsymbol{w}_h) \; \forall \tilde{x} \in \tilde{V}(\mathscr{V})\}$. Since $\bar{v} \in \tilde{V}$, it can be decomposed as

$$\bar{v} = \bar{v}_h + \bar{v}_h^{\perp}, \; \bar{v}_h \in \tilde{V}_h, \; \bar{v}_h^{\perp} \in \tilde{V}_h^{\perp}. \tag{3.27}$$

Since, $T\hat{w}_h \in \tilde{V}_h$, it follows that

$$\begin{aligned} 0 &= (\bar{v}_h^{\perp}, T\hat{w}_h)_{\tilde{V}(\mathscr{V})} && \text{(using } \tilde{V}\text{-orthogonality)} \\ &= b(\bar{v}_h^{\perp}, (0, \hat{w}_h)) && \text{(using (3.22))} \\ &= \langle\langle \bar{v}_h^{\perp}, \hat{w}_h \rangle\rangle && \text{(using (3.24))} \end{aligned} \tag{3.28}$$

and consequently that $\bar{v}_h^\perp \in \bar{V}_h$. Because $T\boldsymbol{w}_h \in \tilde{V}_h$, then, as above,

$$0 = \bar{b}(\bar{v}_h^\perp, \boldsymbol{w}_h). \tag{3.29}$$

By definition of $\bar{v}$

$$\begin{aligned} 0 &= (\bar{v}_h^\perp, \bar{v})_{\tilde{V}(\mathscr{V})} && \text{(by definition)} \\ &= (\bar{v}_h^\perp, \bar{v}_h^\perp)_{\tilde{V}(\mathscr{V})} && \text{(using } \tilde{V}\text{-orthogonality).} \end{aligned}$$

and it is immediate that $\bar{v} = \bar{v}_h \in \tilde{V}_h$.

$\square$

If the optimal conforming PG methodology, §3.1.1, and the DPG methodology are both uniquely solvable, then their solutions are the same because substitution of conforming test functions into the DPG formulation immediately recovers the PG formulation.

3.1.2 A Concrete Example: Linear Advection

Consider the steady linear advection equation as a model problem

$$\boldsymbol{b} \cdot \nabla u = s \qquad \text{in } \Omega, \tag{3.30a}$$

$$u = u_\Gamma \qquad \text{on } \Gamma \coloneqq \{\boldsymbol{x} \in \partial\Omega : \hat{\boldsymbol{n}} \cdot b < 0\}, \tag{3.30b}$$

where $\boldsymbol{b}$ is the advection velocity and $\hat{\boldsymbol{n}}$ is the outward pointing normal vector. Partitioning the domain with N_v non-overlapping volumes, $\mathscr{V}$, with faces, $\mathscr{F}_v \coloneqq \partial\mathscr{V}_v$, such that $\Omega_h = \sum_{v=1}^{N_v}$, (Check notation with Brenner), (3.30a) is multiplied by a test function v and integrated by parts to give the bilinear and linear forms

$$b(v, u) = \sum_{v=1}^{N_v} \int_{\mathscr{V}_v} \nabla v \cdot \boldsymbol{b} u \, d\mathscr{V}_v + \int_{\mathscr{F}_v \cap \Gamma^i} v \hat{\boldsymbol{n}} \cdot \boldsymbol{b} u^* \, d\mathscr{F}_v, \tag{3.31a}$$

$$l(v) = \sum_{v=1}^{N_v} \int_{\mathscr{V}_v} vs \; d\mathscr{V}_v + \int_{\mathscr{F}_v \cap \Gamma} v\hat{\boldsymbol{n}} \cdot \boldsymbol{b} u_\Gamma \; d\mathscr{F}_v, \tag{3.31b}$$

where Γ^i is the set of all internal volume faces (i.e. all faces excluding those in Γ) and where the single-valued solution trace unknowns, u^*, have been introduced.Introducing the *jump* operator, (3.31a) can be expressed more compactly as

$$b(v, u) = \sum_{v=1}^{N_v} \int_{\mathscr{V}_v} \nabla v \cdot \boldsymbol{b} u \; d\mathscr{V}_v + \frac{1}{2} \int_{\mathscr{F}_v} [[\boldsymbol{v}]] \cdot \boldsymbol{b} u^* \; d\mathscr{F}_v, \tag{3.32}$$

where $[[\boldsymbol{v}]] = v^- \hat{\boldsymbol{n}}^- + v^+ \hat{\boldsymbol{n}}^+$ with the additional specification of $v^- \hat{\boldsymbol{n}}^- = v^+ \hat{\boldsymbol{n}}^+$ Check outflow convention from Bui-Thanh

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