

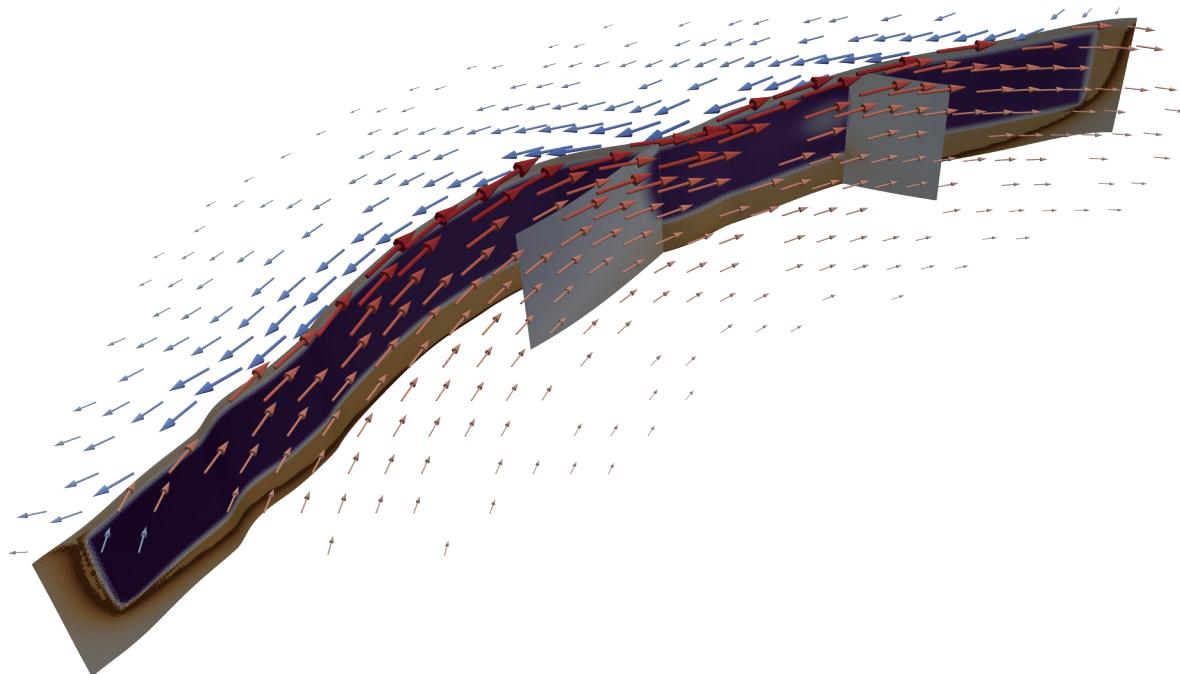


PyQuake3D

3D BOUNDARY ELEMENT METHODS
FOR EARTHQUAKE MODELING

User Manual

Version 1.0.0



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**PyQuake3D: A Python tool for 3-D earthquake sequence
simulations of seismic and aseismic slip**

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Contents

1	Introduction	3
2	Contribution	3
3	Theoretical background	3
3.1	Governing Equations	3
3.2	Hierarchical Matrix Compression and MPI Parallelization in PyQuake3D	6
3.3	Cluster and Block tree construction	7
3.4	Admissibility Condition.....	7
3.5	Low-Rank Approximation of Admissible Blocks	8
3.6	Parallelization of H-matrix Construction and Matrix-Vector Multiplication with MPI	8
3.7	Definition of strike-slip and dip-slip direction.....	9
3.8	Coordinate system.....	10
4	Dependencies	10
5	How to run PyQuake3D	11
5.1	Standard Execution (GPU or CPU).....	11
5.2	MPI-Based Execution (High-Resolution Models)	11
5.3	Parameter Configuration	12
6	Code Structure and File Description	12
6.1	Main Components	12
6.2	Usage Modes	13
6.3	Accelerating Green's Function Calculation with C++	13
7	Parameters setting	13
7.1	Table parameters setting	13
8	Examples	14
9	Stop Control	20
10	Visualization	20
11	License	20
12	Acknowledgments	20

1 Introduction

PyQuake3D is an open-source, Python-based Boundary Element Method (BEM) framework designed to simulate sequences of earthquakes and aseismic slip (SEAS) on geometrically complex three-dimensional (3D) fault systems governed by rate- and state-dependent friction laws. It supports fully arbitrary fault geometries embedded in either a uniform elastic half-space or full-space medium, including non-planar surfaces, fault stepovers, branches, and roughness. This document provides a general overview of PyQuake3D, including its main capabilities, usage instructions, and a detailed description of the required input parameters.

Two implementations of the code are currently available:

- **GPU-accelerated version:** Utilizes Python’s `ProcessPoolExecutor` for parallel evaluation of Green’s functions (kernels), and leverages GPU-based linear algebra libraries (`CuPy`) to accelerate dense matrix–vector operations.
- **H-matrix + MPI version:** Reduces memory footprint and computational cost using hierarchical matrix (H-matrix) compression via Adaptive Cross Approximation (ACA). Distributed parallelism is implemented with MPI (`mpi4py`) to enable efficient large-scale simulations on high-performance computing (HPC) platforms.

PyQuake3D is designed to scale from local workstations to HPC clusters, making it a flexible and extensible platform for researchers, students, and educators interested in exploring the physics of earthquake cycles across a wide range of spatial and temporal scales.

2 Contribution

PyQuake3D was developed by Rongjiang Tang and Luca Dal Zilio, who implemented the core framework, including the Boundary Element Method for simulating seismic cycles on geometrically complex 3D faults governed by a regularized rate-and-state friction governed by aging law. The software also features MPI-based hierarchical matrix compression and GPU acceleration for scalable performance. We welcome contributions from the research community. Please follow the contribution guidelines and ensure consistency with the existing codebase. The project is under active development, and we encourage feedback and collaborative extensions. PyQuake3D is distributed under an open-source license to support reproducibility and broad adoption in earthquake science. If you use PyQuake3D in your research, please cite the corresponding reference to acknowledge the original work.

3 Theoretical background

3.1 Governing Equations

To solve the earthquake dynamic simulation problem using boundary integral equations, we assume the fault plane is embedded in an elastic half-space or full-space with homogeneous and constant elastic moduli and constant tectonic loading rate is imposed across the whole fault interface. The elastic stress transfer due to slip on the fault is described in Equations 1 (shear stress) and 2 (normal stress), with the radiation damping assumption [Rice, 1993]:

$$\tau_i = \tau_0 - \sum_{j=1}^n k_{ij}^s (u_j - V_{plt}) - \frac{\mu}{2c_s} \frac{\partial u_i}{\partial t} \quad (1)$$

$$\bar{\sigma}_i = \bar{\sigma}_0 + \sum_{j=1}^n k_{ij}^N (u_j - V_{pl}t) \quad (2)$$

where V_{pl} is the imposed tectonic slip rate, μ is the shear modulus, c_s is the shear wave speed, and u_j is the slip at the j -th element. The kernels k_{ij}^s and k_{ij}^N represent the shear and normal stiffness matrices, respectively. The last term in Equation 1 captures radiation damping and approximates inertial effects, which is adopted to avoid the unbounded slip velocity that would otherwise develop as a consequence of instability in a quasi-static model [Rice, 1993].

To compute the k_{ij}^s and k_{ij}^N , we employ analytical formulas for static stress induced by triangular dislocations in a homogeneous elastic full-space and half-space, as described by [Nikkhoo and Walter, 2015]. Since our objective is to simulate three-dimensional complex non-planar fault geometries, optimizations specific to planar faults, such as constructing K in the Fourier domain [Rice, 1993] and leveraging translational invariance to compute stresses as convolutions using the Fast Fourier Transform, are not applicable. Instead, we utilize CPU-based multiprocessing or MPI to accelerate the computation of Green's functions required for generating the stiffness matrix.

To construct the differential equation, we take the time derivative of equation Equation 1 and 2, while considering the external stress loading.

$$\frac{d\tau_i}{dt} = - \sum_{j=1}^N k_{ij}^s (V_j - V_{pl}) + \dot{\tau}_i - \frac{\mu}{2c_s} \frac{dV_i}{dt} \quad (3)$$

$$\frac{d\sigma_i}{dt} = \sum_{j=1}^N k_{ij}^N V_j + \dot{\sigma}_i \quad (4)$$

Where the $\dot{\tau}_i$ and $\dot{\sigma}_i$ represent the tectonic loading rates for shear and normal stress on the i -th fault cell, respectively.

To solve the differential Equation 3 and 4, we need to incorporate the boundary conditions governed by the laboratory-derived rate- and state-dependent friction law (RSF) [Dieterich, 1979, Ruina, 1983]. The friction coefficient is given by a regularized aging law formulation:

$$f(V, \theta) = a \sinh^{-1} \left[\frac{V}{2V_0} \exp \left(\frac{f_0 + b \ln \left(\frac{V_0 \theta}{d_c} \right)}{a} \right) \right] \quad (5)$$

$$\frac{d\theta}{dt} = 1 - \frac{V\theta}{d_c} \quad (6)$$

Where d_c represents the characteristic slip distance, V_0 the reference slip rate, f_0 the reference friction coefficient, θ the state variable. The parameters a and b are used to depict the direct and evolution effects of shear resistance during and following a velocity step.

To simplify, we replace the state variables θ with ψ

$$\psi = f_0 + b \ln \left(\frac{V_0 \theta}{d_c} \right) \quad (7)$$

Then, we obtain the transformed friction relation:

$$\frac{\tau_i}{\sigma_i} = a \arcsin(h) \left(\frac{V_i}{2V_0} \exp \left(\frac{\psi_i}{a} \right) \right) \quad (8)$$

$$\frac{d\psi_i}{dt} = \frac{b}{d_c} \left[V_0 \exp \left(\frac{f_0 - \psi_i}{b} \right) - V_i \right] \quad (9)$$

Let's return to Equation 3. The $\frac{dV_i}{dt}$ can be replaced using the chain rule.

$$\frac{dV_i}{dt} = \frac{\partial V_i}{\partial \tau_i} \frac{d\tau_i}{dt} + \frac{\partial V_i}{\partial \sigma_i} \frac{d\sigma_i}{dt} + \frac{\partial V_i}{\partial \psi_i} \frac{d\psi_i}{dt} \quad (10)$$

Then we obtain final form of the shear stress variation

$$\frac{d\tau_i}{dt} = \left(1 + \frac{\mu}{2c_s} \frac{\partial V_i}{\partial \tau_i} \right)^{-1} \left[\sum_{j=1}^N k_{ij}^s V_j + \dot{\tau}_i - \frac{\mu}{2c_s} \left(\frac{\partial V_i}{\partial \sigma_i} \frac{d\sigma_i}{dt} + \frac{\partial V_i}{\partial \psi_i} \frac{d\psi_i}{dt} \right) \right] \quad (11)$$

Shear stress can be decomposed in both strike-slip and dip-slip directions τ_1 and τ_2 , and V_1 and V_2 refer to the slip rates in both directions

$$\frac{d\tau_{1,i}}{dt} = \left(1 + \frac{\mu}{2c_s} \frac{\partial V_{1,i}}{\partial \tau_{1,i}} \right)^{-1} \left[\sum_{j=1}^N k_{ij}^{s1} V_{1,j} + \dot{\tau}_{1,i} - \frac{\mu}{2c_s} \left(\frac{\partial V_{1,i}}{\partial \sigma_i} \frac{d\sigma_i}{dt} + \frac{\partial V_{1,i}}{\partial \psi_i} \frac{d\psi_i}{dt} \right) \right] \quad (12)$$

$$\frac{d\tau_{2,i}}{dt} = \left(1 + \frac{\mu}{2c_s} \frac{\partial V_{2,i}}{\partial \tau_{2,i}} \right)^{-1} \left[\sum_{j=1}^N k_{ij}^{s1} V_{2,j} + \dot{\tau}_{2,i} - \frac{\mu}{2c_s} \left(\frac{\partial V_{2,i}}{\partial \sigma_i} \frac{d\sigma_i}{dt} + \frac{\partial V_{2,i}}{\partial \psi_i} \frac{d\psi_i}{dt} \right) \right] \quad (13)$$

Where

$$\frac{\partial V_{1,i}}{\partial \tau_{1,i}} = \frac{2V_0}{a\sigma_i} \exp \left(-\frac{\psi_i}{a} \right) \cosh \left(\frac{\tau_{1,i}}{a\sigma_i} \right) \quad (14)$$

$$\frac{\partial V_{2,i}}{\partial \tau_{2,i}} = \frac{2V_0}{a\sigma_i} \exp \left(-\frac{\psi_i}{a} \right) \cosh \left(\frac{\tau_{2,i}}{a\sigma_i} \right) \quad (15)$$

$$\frac{\partial V_{1,i}}{\partial \sigma_i} = -\frac{2V_0 \tau_{1,i}}{a\sigma_i^2} \exp \left(-\frac{\psi_i}{a} \right) \cosh \left(\frac{\tau_{1,i}}{a\sigma_i} \right) \quad (16)$$

$$\frac{\partial V_{2,i}}{\partial \sigma_i} = -\frac{2V_0 \tau_{2,i}}{a\sigma_i^2} \exp \left(-\frac{\psi_i}{a} \right) \cosh \left(\frac{\tau_{2,i}}{a\sigma_i} \right) \quad (17)$$

$$\frac{\partial V_{1,i}}{\partial \psi_i} = -\frac{2V_0}{a} \exp \left(-\frac{\psi_i}{a} \right) \sinh \left(\frac{\tau_{1,i}}{a\sigma_i} \right) \quad (18)$$

$$\frac{\partial V_{2,i}}{\partial \psi_i} = -\frac{2V_0}{a} \exp \left(-\frac{\psi_i}{a} \right) \sinh \left(\frac{\tau_{2,i}}{a\sigma_i} \right) \quad (19)$$

We use backslip method ([Heimisson, 2020]) with a plate rate V_{pl} for plate motion loading, such that $V_{1,i}$ and $V_{2,i}$ can be replaced by $V_{1,i} - V_{pl,i}$ and $V_{2,i} - V_{pl,i}$. By substituting Equation 14 to 19 into Equation 12 and 13, Equation 4, 9, 12 and 13 can form a system of ordinary differential equations with a dimensional size of $4N$:

$$\frac{dy}{dt} = f(y) \quad (20)$$

$$y = (\psi_1, \dots, \psi_N, \tau_{1,1}, \dots, \tau_{1,N}, \tau_{2,1}, \dots, \tau_{2,N}, \sigma_1, \dots, \sigma_N) \quad (21)$$

We solve these equations using the Dormand-Prince 5th-order Runge–Kutta method with adaptive time stepping [Press et al., 2007]. After each iteration, other important variables such as the slip velocity, shear traction amplitude and rake angle are updated by the following formula:

$$\tau = \sqrt{\tau_1^2 + \tau_2^2} \quad (22)$$

$$V_1 = 2V_0 \cdot \exp\left(-\frac{\psi}{a}\right) \cdot \sinh\left(\frac{\tau_1}{\sigma}\right) \quad (23)$$

$$V_2 = 2V_0 \cdot \exp\left(-\frac{\psi}{a}\right) \cdot \sinh\left(\frac{\tau_2}{\sigma}\right) \quad (24)$$

$$V = \sqrt{V_1^2 + V_2^2} \quad (25)$$

$$\text{rake} = \arctan\left(\frac{\tau_2}{\tau_1}\right)$$

To implement the adaptive time step, we calculate the time step for the next iteration h_{n+1} based on the relative error between the 4- and 5-order Runge–Kutta formulas.

$$h_{n+1} = Sh_n \left(\frac{\epsilon_0}{\epsilon_k} \right)^{0.2} \quad (26)$$

where the safety factor $S = 0.9$, and $\epsilon_0 = 10^{-4}$ is the set threshold to determine whether the desired precision has been achieved. The relative error is given by

$$\epsilon_k = \max \left(\left| \frac{y_{n+1} - y_{n+1}^*}{y_{n+1}} \right| \right) \quad (27)$$

Here y_{n+1}^* is the result of the fifth order computation and y_{n+1} is the result of the fourth order computation. For each Runge–Kutta iteration, we first check if $C = \frac{\epsilon_0}{\epsilon_k}$ is less than 1. If it is, we update the time step using Equation 26 and then constrain the $h_{n+1} = \min(1.5h_n, h_{n+1})$. Otherwise, we update the step size using 26 then constrain the $h_{n+1} = \max(0.5h_n, h_{n+1})$. The Runge–Kutta iteration is re-executed until the C becomes less than 1.0 or the maximum number of iterations is reached.

3.2 Hierarchical Matrix Compression and MPI Parallelization in PyQuake3D

According to Börm’s foundational work [Börm et al., 2003], PyQuake3D implements a Python-based H-matrix framework from the ground up. The implementation, contained in the `Hmatrix.py` module, supports MPI-based parallel acceleration and is designed with modularity, making it easily separable and adaptable for use in other applications.

The core idea of the H-matrix is to apply low-rank approximation to far-field submatrices while keep the dense near-field submatrices. Therefore, the essential purpose is to decompose the original matrix in a reasonable and efficient manner and to identify the submatrices suitable for low-rank approximation. The structure of the H-matrix is built upon a cluster tree and a block tree. The construction begins with generating a cluster tree based on the element index, which is then used to form the block cluster tree through pairwise combinations of the clusters. The implementation of H-matrices in *PyQuake3D* includes four parts: cluster tree construction, block cluster tree generation, low-rank approximation, as well as MPI acceleration.

3.3 Cluster and Block tree construction

A simple method of building a cluster tree is based on geometry-based splittings of the index set. The unit coordinates in 3D space are the basis e_x, e_y, e_z of the canonical unit vectors. The following algorithm will split a given cluster $\tau \subset I$ into two sons such that the points with canonical coordinate x_i are separated by a hyper-plane (Algorithm 1).

Algorithm 1 Geometric Splitting of an Index Cluster

```

1: procedure SPLIT( $\tau$ , var  $\tau_1$ , var  $\tau_2$ )
2:                                      $\triangleright$  Choose a direction for geometrical splitting of the cluster  $\tau$ 
3:   for  $j := 1$  to  $d$  do
4:      $\alpha_j := \min\{\langle e_j, x_i \rangle : i \in \tau\}$                                  $\triangleright \langle \cdot, \cdot \rangle$  is the  $\mathbb{R}^d$  Euclidean product,  $d = 3$ 
5:      $\beta_j := \max\{\langle e_j, x_i \rangle : i \in \tau\}$ 
6:   end for
7:    $j_{\max} := \arg \max\{\beta_j - \alpha_j : j \in \{1, \dots, d\}\}$                        $\triangleright$  Split the cluster  $\tau$  in the chosen direction
8:
9:    $\gamma := (\alpha_{j_{\max}} + \beta_{j_{\max}})/2$ 
10:   $\tau_1 := \emptyset$ ;  $\tau_2 := \emptyset$ 
11:  for  $i \in \tau$  do
12:    if  $\langle e_{j_{\max}}, x_i \rangle \leq \gamma$  then
13:       $\tau_1 := \tau_1 \cup \{i\}$ 
14:    else
15:       $\tau_2 := \tau_2 \cup \{i\}$ 
16:    end if
17:  end for
18: end procedure

```

The cluster tree can be used to define a block tree by forming pairs of clusters recursively, and an admissibility condition is constructed by the following procedure (Algorithm 2):

For a pair of index clusters (τ, σ) , the corresponding submatrix is $A_{\tau, \sigma}$. These matrix blocks are organized into a block cluster tree, which guides the hierarchical representation of A . If the clusters t and s are both non-leaf nodes with children t_1, t_2 and s_1, s_2 respectively, the submatrix A_{ts} can be further decomposed into four submatrices (Figure 1a).

Algorithm 2 Build BlockTree

```

procedure BUILDBLOCKTREE( $\tau \times \sigma$ )
begin
  if  $\tau \times \sigma$  is not admissible and  $|\tau| > C_{\text{leaf}}$  and  $|\sigma| > C_{\text{leaf}}$  then
    begin
       $S(\tau \times \sigma) := \{\tau' \times \sigma' : \tau' \in S(\tau), \sigma' \in S(\sigma)\}$ 
      for  $\tau' \times \sigma' \in S(\tau \times \sigma)$  do
        BuildBlockTree( $\tau' \times \sigma'$ )
      end for
    end
  else
     $S(\tau \times \sigma) := \emptyset$ 
  end if
  end
end procedure

```

3.4 Admissibility Condition

Matrix blocks $A_{\tau, \sigma}$ are classified into *admissible* and *inadmissible* based on the geometric configuration of τ and σ . we need an admissibility condition that allows us to check if a candidate $(\tau \times \sigma)$ allows for

a suitable low rank approximation (Algorithm 2).

A relatively general and practical admissibility condition for clusters in \mathbb{R}^d can be defined by using bounding boxes: We define the canonical coordinate maps

$$\pi_k : \mathbb{R}^d \rightarrow \mathbb{R}, \quad x \mapsto x_k,$$

for all $k \in \{1, \dots, d\}$ ($d=3$ in 3D space). The bounding box for a cluster τ is then given by

$$Q_\tau := \prod_{k=1}^d [a_{\tau,k}, b_{\tau,k}], \quad \text{where } a_{\tau,k} := \min(\pi_k \Omega_\tau) \quad \text{and} \quad b_{\tau,k} := \max(\pi_k \Omega_\tau).$$

Obviously, $a_{\tau,k}$ and $b_{\tau,k}$ are the minimum and maximum value in the k -th dimension of the coordinate set Ω_τ , we have $\Omega_\tau \subseteq Q_\tau$, so we can define the admissibility condition

$$\min\{\text{diam}(Q_\tau), \text{diam}(Q_\sigma)\} \leq \eta \text{dist}(Q_\tau, Q_\sigma) \quad (28)$$

We can compute the diameters and distances of the boxes by

$$\text{diam}(Q_\tau) = \left(\sum_{k=1}^d (b_{\tau,k} - a_{\tau,k})^2 \right)^{1/2} \quad \text{and} \quad (29)$$

$$\text{dist}(Q_\tau, Q_\sigma) = \left(\sum_{k=1}^d (\max(0, a_{\tau,k} - b_{\sigma,k})^2 + \max(0, a_{\sigma,k} - b_{\tau,k})^2) \right)^{1/2}. \quad (30)$$

3.5 Low-Rank Approximation of Admissible Blocks

When calculating the stress Green's function, we need to avoid constructing the full dense BEM matrix by Low-Rank Approximation. This can be helpful for reducing memory costs and, in some situations, actually results in a faster solver too. Singular value decomposition (SVD) is an extremely efficient approximation, but it still suffers from the need to compute the entire matrix block in the first place, an $O(n^2)$ operation!

The most useful solution for our setting is the adaptive cross approximation (ACA) method [Bebendorf, 2000, Rjasanow and Steinbach, 2007], but most real-world application use either *ACA with partial pivoting* or the *ACA+* algorithm.[Grasedyck, 2005]. The basic idea of ACA+ is to approximate a matrix with a rank 1 outer product of one row and one column of that same matrix, and then iteratively use this process to construct an approximation of arbitrary precision. ACA+ uses orthogonal projections and recompression to better control the error and avoid poor pivot choices, and improves the stability and accuracy of the standard ACA.

3.6 Parallelization of H-matrix Construction and Matrix-Vector Multiplication with MPI

We construct the cluster tree, block cluster tree, and establish the overall H-matrix framework. This includes the initial distribution of the index sets and the assignment of matrix blocks. Once the hierarchical structure is built, the matrix blocks are distributed across different MPI processes for parallel computation of elements (e.g., `MPI_send`, `MPI_recv`). We adopt a dynamic task allocation strategy in MPI to mitigate load imbalance issues that may arise from static task assignment (Figure 1d).

Each process is responsible for computing the entries of its assigned matrix blocks. For admissible blocks, a low-rank approximation is performed using the ACA algorithm. For non-admissible blocks, typically corresponding to leaf nodes in the block cluster tree, are the full dense matrix computed by evaluating all pairwise Green's function interactions between source and target elements (Figure 1c). .

During matrix-vector multiplication, each process independently computes the product of its local matrix blocks with the corresponding portion of the input vector. The final global result vector is then obtained by summing the local contributions across all processes (`MPI_reduce`) (Figure 1e).

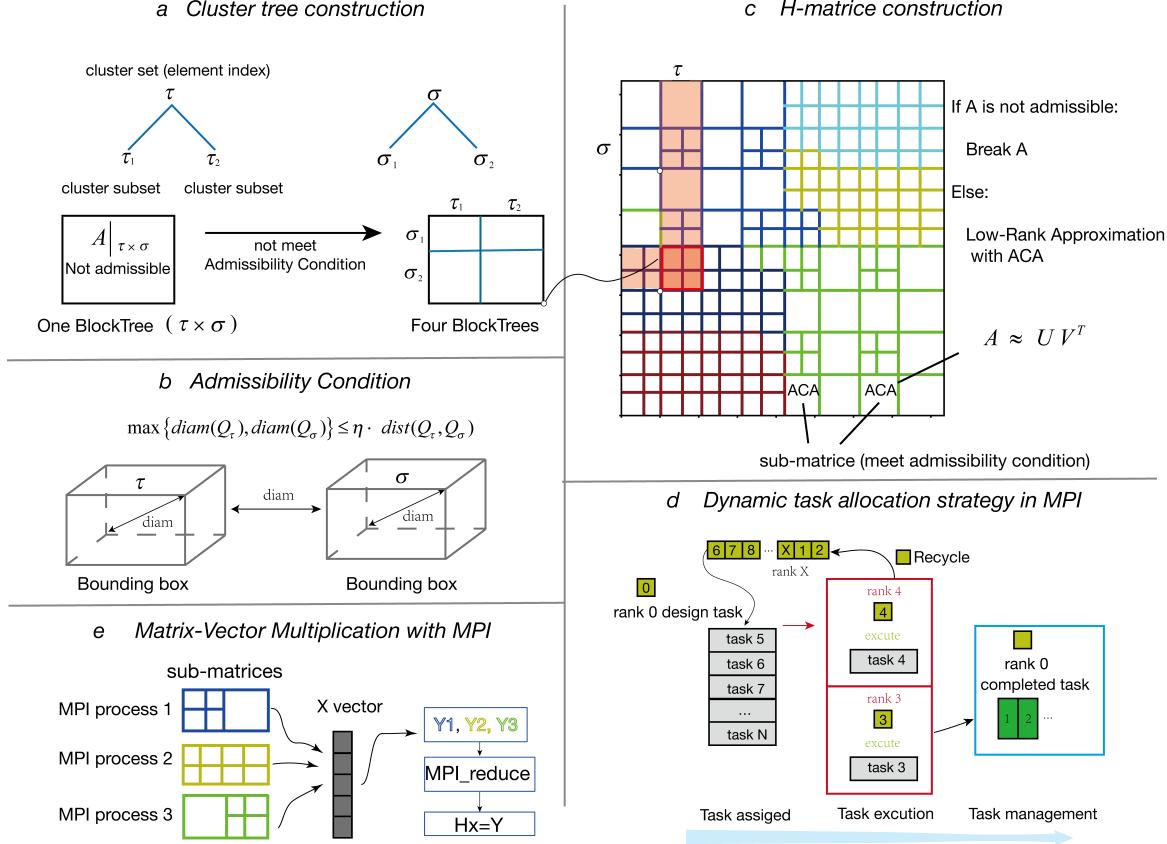


Figure 1: Construction of hierarchical matrix speed up by MPI

3.7 Definition of strike-slip and dip-slip direction

The rake angle is defined as the angle between the fault slip vector and the fault strike direction within the fault plane. In seismology, the strike direction is conventionally defined: when facing the dip direction of the fault plane, the strike is taken to be to the observer's right—this follows the right-hand rule. In *PyQuake3D*, the strike direction is determined by the ordering of the element's nodes—either clockwise or counterclockwise. To get the defined strike-slip direction for each element, we first calculate the normal vector of the element in the global coordinate system by

$$\vec{e}_3 = \vec{v}_{ab} \times \vec{v}_{ac} \quad (31)$$

Based on the geometric relationship of \vec{e}_1 and \vec{e}_3 (Figures 2b,c), the three component of strike-slip direction of the fault cell (x-direction of the local coordinate system) can be obtained by

$$\begin{aligned} e_{11} &= e_{32} \\ e_{12} &= -e_{31} \\ e_{13} &= 0 \end{aligned} \quad (32)$$

Then we can easily get the last direction (dip-slip direction) of the fault element get by

$$\vec{e}_2 = \vec{e}_3 \times \vec{e}_1 \quad (33)$$

Figures 2d and e and d show that the definition of strike slip and dip slip directions obviously depends on the ordering of nodes, so when modeling, we need to first clarify the ordering direction of nodes, and then determine the definition of fault slip direction.

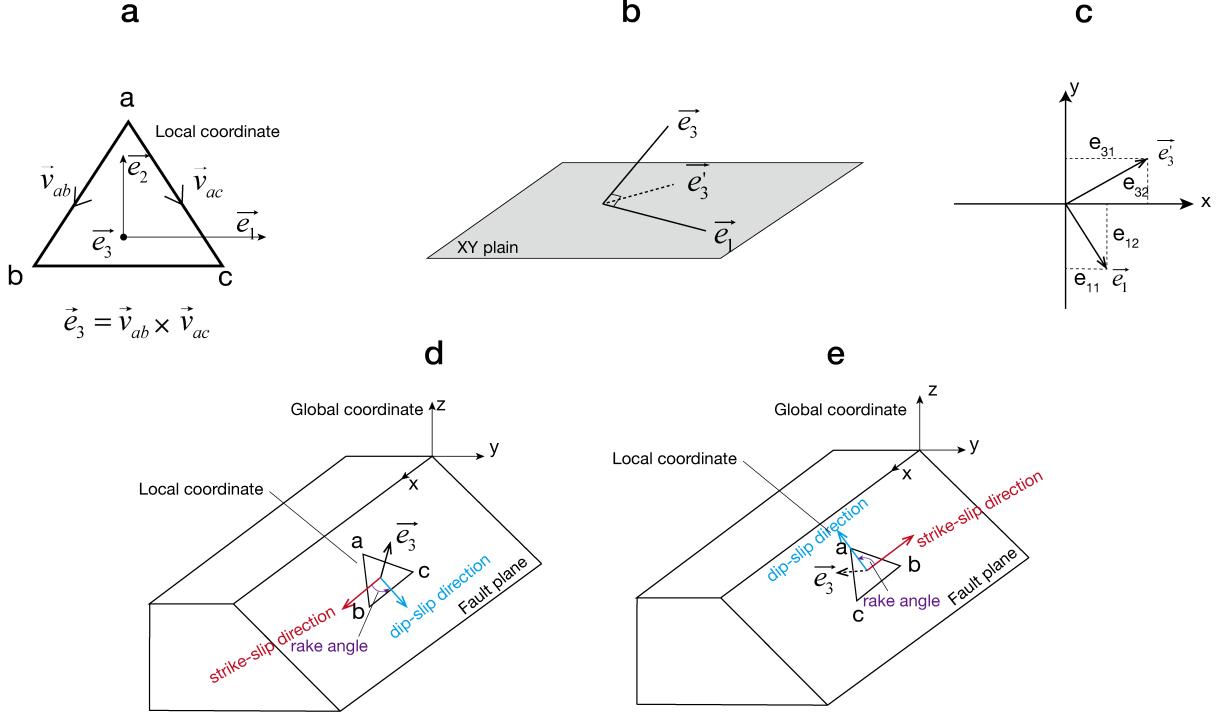


Figure 2: Definition of strike-slip and dip-slip direction. (a) Calculation of normal vector or z-vector in element local coordinate system \vec{e}_3 . (b) Projection of \vec{e}_3 on XY plane \vec{e}'_3 . (c) Conversion between \vec{e}'_3 and \vec{e}_1 . (d)

3.8 Coordinate system

In post-processing, we need to do transforms between local and global coordinates for some vector results, such as slip direction. Base on the relationship in Figure 2d and e, the transform from local coordinates to global coordinates can be obtained by coordinate rotation.

$$\begin{bmatrix} e_{11} & e_{21} & e_{31} \\ e_{12} & e_{22} & e_{32} \\ e_{13} & e_{23} & e_{33} \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix} = \begin{bmatrix} X_1 \\ X_2 \\ X_3 \end{bmatrix} \quad (34)$$

Where x is a vector of local coordinates and X is a vector of global coordinates.

4 Dependencies

PyQuake3D is implemented in Python and requires the following packages for successful installation and execution:

In most environments, core libraries such as NumPy are pre-installed with Python distributions. To install all required dependencies, simply run:

Package	Version Requirement
python	≥ 3.8
numPy	≥ 1.20
cuPy	$\equiv 10.6.0$
matplotlib	$\equiv 3.2.2$
sciPy	$\equiv 1.10.1$
joblib	$\equiv 1.2.0$
mpi4py	$\equiv 4.0.3$
ctypes	$\equiv 1.1.0$
pyvista	$\equiv 0.45.2$

Table 1: Required dependencies for running PyQuake3D.

```
pip install -r dependences.txt
```

Ensure that the correct Python environment is activated before installation, especially when using virtual environments or managing dependencies with tools such as `conda` or `venv`.

5 How to run PyQuake3D

To get started, clone the PyQuake3D repository from GitHub:

```
https://github.com/Computational-Geophysics/PyQuake3D
```

PyQuake3D can be executed either in standard Python mode or in MPI-parallel mode, depending on the size and resolution of your model. All simulations are launched from the project's root directory using the `main.py` script located in the `src` folder.

5.1 Standard Execution (GPU or CPU)

To run a simulation using the standard execution mode (with optional GPU acceleration), use the following command:

```
python src/main.py -g <input_geometry_file> -p <input_parameter_file>
```

For example, to execute the benchmark simulation BP5-QD:

```
python src/main.py -g examples/BP5-QD/bp5t.msh -p examples/BP5-QD/parameter.txt
```

5.2 MPI-Based Execution (High-Resolution Models)

For large-scale simulations using the MPI-parallel H-matrix version, use the following command:

```
mpirun -np <N> python src/main.py -g <input_geometry_file> -p <input_parameter_file>
```

For example, using 10 parallel processes:

```
mpirun -np 10 python src/main.py -g examples/BP5-QD/bp5t.msh -p examples/BP5-QD/parameter.txt
```

Note: On Windows systems, replace `mpirun` with `mpiexec`. In the MPI version, the stress Green's function is implemented in C++ and invoked from Python. On Linux systems, the shared library `TDstressFS_C.so` has already been compiled. On Windows systems, however, it is necessary to compile `src/TDstressFS_C.cpp` into a DLL before it can be imported in `Hmatrix.py` (see line 21). For the MPI version, it is recommended to run the program in a Linux environment.

5.3 Parameter Configuration

Each example folder contains a `parameter.txt` file, which defines the model settings, material properties, and solver options. Ensure this file is correctly configured before launching a simulation. A detailed explanation of the parameter settings is provided in Section 7.

6 Code Structure and File Description

The PyQuake3D source code is organized to reflect its modular architecture and hybrid parallel computing design (Figure 3). All core Python modules are located in the `src` directory, while model configurations and parameter files are provided in the `examples` folder. The `examples` directory contains predefined models, including the BP5-QD benchmark based on the Southern California Earthquake Center's SEAS community validation project¹.

6.1 Main Components

The PyQuake3D codebase is structured around distinct computational tasks:

- `main.py`: Entry point for running the quasi-dynamic simulations. It handles the model setup, time integration, and output generation. Users may customize this script for advanced diagnostics or automated post-processing.
- `QDsim.py`: Defines the `QDsim` class, which encapsulates the governing equations, numerical integrator, and interface to the selected Green's function backend (dense or hierarchical).
 - `QDsim.Init_condition()`: Setting initial condition of fault model.
 - `QDsim.simu_forward()`: Model forward calculation.
- `DH_Greenfunction.py` and `SH_Greenfunction.py`: Compute the displacement and stress Green's functions for homogeneous elastic half-space and full-space media, respectively.
- `TDstressFS_C.cpp`: Compute the stress Green's functions for homogeneous elastic half-space and full-space media using C++ language.
- `Hmatrix.py`: Constructs and applies the hierarchical matrix representation based on Adaptive Cross Approximation (ACA), optimized for distributed-memory parallelism using `mpi4py`.
 - `QDsim.create_recursive_blocks()`: Recursively build the blocktree.
 - `QDsim.createHmatrix()`: Build the Hmatrix.
 - `tree_block.master()`: Dynamically allocate MPI tasks
 - `tree_block.worker()`: Execute MPI tasks of calculating stress green's functions.
 - `tree_block.tree_block.parallel_block_scatter_send()`: Distribute sub-matrices of the fully built Hmatrix to each process.
- `Readmsh.py`: Parses unstructured mesh files (in `.msh` format) and imports model geometry, fault segmentation, and material parameters.

¹<https://strike.scec.org/cvws/seas/download/>

6.2 Usage Modes

PyQuake3D supports two execution backends:

- **GPU-based backend:** Constructs dense stiffness matrices using direct evaluation of all source–receiver interactions. GPU acceleration is implemented via CuPy, and parallelism is handled using Python’s `ProcessPoolExecutor` for kernel evaluations.
- **MPI-based CPU backend:** Implements a memory-efficient H-matrix representation of the stiffness matrix, distributed across multiple processors using `mpi4py`. This version is well-suited for simulations with >40,000 elements and optimized for HPC systems.

This structure allows users to scale from fast exploratory models on local machines to high-resolution, physics-rich earthquake simulations on supercomputing clusters. The modular design also facilitates extension of the framework to include additional rheologies, boundary conditions, or coupling with geodynamic models.

6.3 Accelerating Green’s Function Calculation with C++

The computation of Green’s functions involves a large number of scientific calculations, where Python generally performs less efficiently compared to C/C++. To enhance computational efficiency, *PyQuake3D* provides a C++ implementation of the Green’s function (in the file `TDstressFS_C.cpp`), which has been compiled into a dynamic library `TDstressFS_C.o` and can be accessed using Python’s `ctypes` interface. If modifications to the source code are necessary, the updated version must be recompiled using a `Makefile` before it can be executed.

7 Parameters setting

7.1 Table parameters setting

The simulation parameters are implemented by modifying the `parameter.txt` file, rather than by changing the source code. The input variable list is in *Table 2*. If `InputHetoparamter` in *Table 2* is True, heterogeneous stress and friction parameters are imported from external files. The external filename is defined in `parameter.txt` and must remain in the same directory as `parameter.txt`. In this case, you only need to appropriately set parameter of *Table 2* and *Table 5*. Otherwise, you need to appropriately set the parameters of stress and frictional initial condition shown in *Table 3* and *Table 4*.

External file format

In addition to `parameter.txt`, the program requires external the `.msh` file for geometry, as well as `Inputparameterfiles` if `Input Hetoparamter` is set to True. The filename for `Inputparameterfiles` is defined within `parameter.txt`.

The `.msh` file contains necessary mesh data such as node coordinates, element numbers, and other relevant information. It is exported from *Gmsh* software. Please ensure selecting the *Version2/ASCII* format to match the code’s reading program.

When `InputHetoparameter == True`, the initial condition can be imported externally (via the Input-parameter file):

```
rake(0) a(0) b(0) dc(0) f0(0) tau(0) sigma(0) vel(0) taudot(0) sigdot(0)
rake(1) a(1) b(1) dc(1) f0(1) tau(1) sigma(1) vel(1) taudot(1) sigdot(1)
...
```

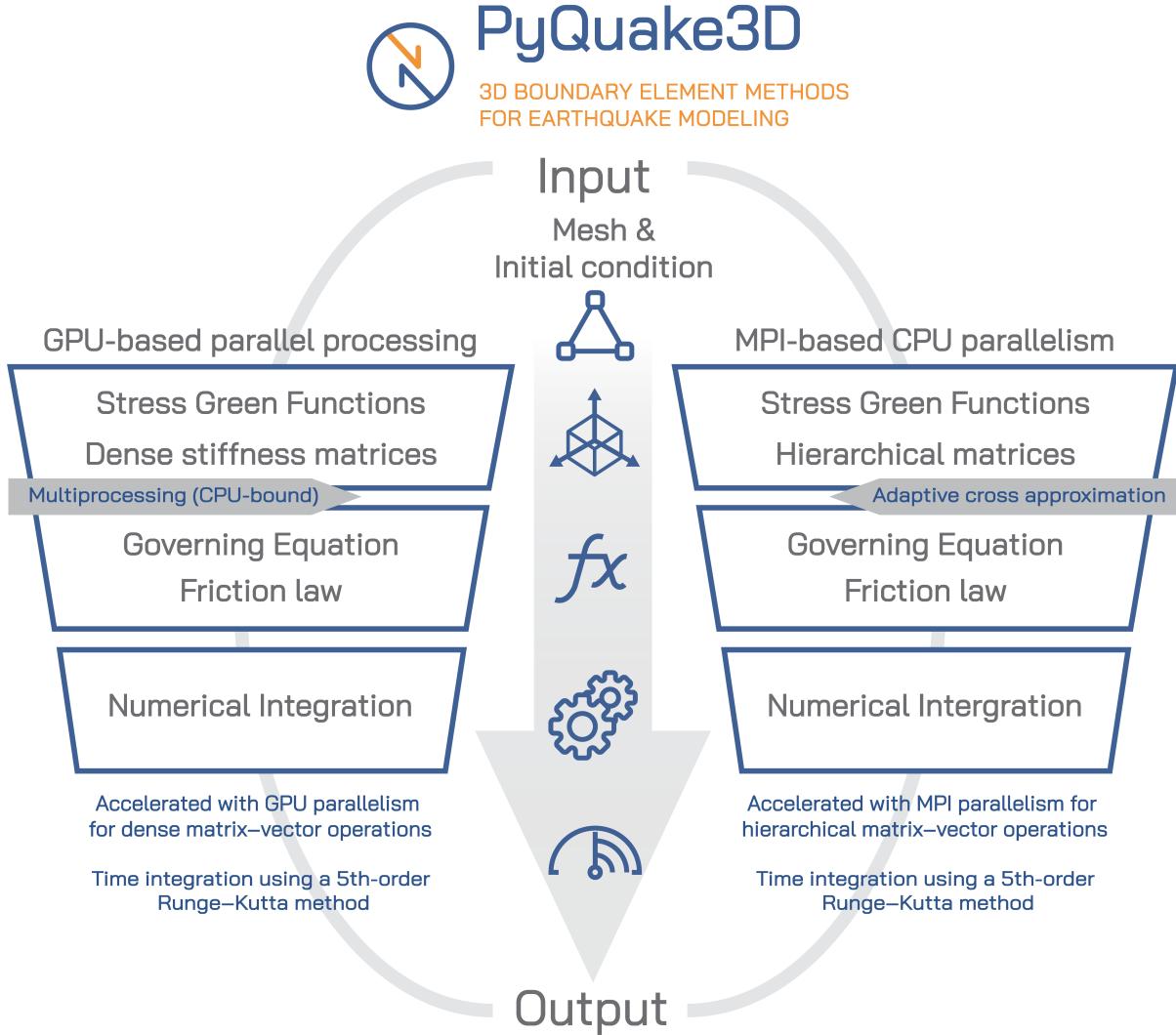


Figure 3: Overview of the PyQuake3D computational framework. The workflow includes input setup, solver implementation on GPU or CPU architectures, and output diagnostics. The GPU version uses dense matrix–vector operations accelerated with CUDA, while the CPU version applies hierarchical matrix compression and MPI-based parallelism.

The total number of rows in the *InputHeteroparameter* file is equal to the number of cells. The first column represents the rake angle, which varies in the calculation process. Columns 2, 3, 4, and 5 represent parameters related to the rate-state friction law: frictional parameters a , frictional parameters a , characteristic slip dc , reference friction coefficient. Columns 6 and 7 denote shear and normal tractions, respectively. Column 8 is the initial slip rate, and the last two columns represent the loading rates for shear and normal tractions. Note that this loading refers to additional loading other than the slip deficit rate loading, with a default value of 0.

8 Examples

Let's consider first the heterogeneous frictional model (HF) to compute the earthquake cycle of strike-slip fault using MPI-based PyQuake3D (Figure 4). Listing 1 shows the entire input file required to describe the simulation. Note how the code is called, with the command

Table 2: General Parameters

Parameter	Default	Description
<code>Corefunc directory</code>		The storage path for the kernel function matrix composed of stress Green's functions
<code>Hmatrix_mpi_plot</code>	False	If ‘True‘, draw the Hmatirx structure diagram, with different colors representing the sub-matrices calculated by different processes. Only available for MPI verison.
<code>Node_order</code>	False	If ‘True‘, the node order of the triangular element is clockwise
<code>save Corefunc</code>	False	If ‘True‘, save corefuns Save the kernel function so that it does not need to be recalculated for the next time
<code>Scale_km</code>	True	If ‘True‘, the coordinates will be scaled up by a factor of 1000, meaning they are modeled in kilometers, which is applicable to natural earthquakes; otherwise, the coordinates remain unchanged, meaning they are modeled in meters, which is applicable to laboratory earthquakes.
<code>Input Hetoparamter</code>	False	If ‘True‘, the heterogeneous stress and friction parameters are imported from external files.
<code>Inputparamter file</code>		The file name of imported heterogeneous stress and friction parameters
<code>Processors</code>	50	The number of processors in ProcessPoolExecutor to parallelize Green’s function calculations. Only available for GPU verison.
<code>Batch_size</code>	1000	The number of batches in ProcessPoolExecutor to parallelize Green’s function calculations. Only available for GPU verison.
<code>Lame constants</code>	0.32×10^{11} Pa	The first Lame constant
<code>Shear modulus</code>	0.32×10^{11} Pa	Shear modulus
<code>Rock density</code>	2670 kg/m^3	Rock mass density
<code>Reference slip rate</code>	1×10^{-6}	Reference slip rate
<code>Reference friction coefficient</code>	0.6	Reference friction coefficient
<code>Plate loading rate</code>	1×10^{-9}	Plate loading rate

```
mpirun -np 12 python src/main.py -g examples/HF-model/HFmodel.msh -p examples/HF-model/parameter.txt
```

In this case, the program is called with 12 CPUs for MPI parallel computing. After the program starts, it outputs screen information as shown in Listing 2. The screen output consists of three main parts:

- 1. Basic Information:** This section provides a summary of the key model settings, allowing users to verify the correctness of the configuration.
- 2. MPI-Based Dynamic Process Allocation:** This section displays the status of each process during the parallel computation of Green’s functions, offering insight into how tasks are distributed across different MPI ranks.
- 3. Numerical Integration of the Governing Equations:** Upon completion of the Green’s function computation, the program proceeds to solve the differential equations using the Runge-Kutta

Table 3: Stress and Frition Settings

Parameter	Default	Description
Half space	False	If 'True', calculating half-space green's functions
Fix_Tn	True	If 'True', fixed the normal stress
Vertical principal stress (ssv)	1.0	The vertical principal stress scale: the real vertical principal stress is obtained by multiplying the scale and the value
Maximum horizontal principal stress (ssh1)	1.6	Maximum horizontal principal stress scale.
Minimum horizontal principal stress(ssh2)	0.6	Minimum horizontal principal stress scale
Angle between ssh1 and X-axis	30°	Angle between maximum horizontal principal stress and X-axis.
Vertical principal stress value	50 MPa	Vertical principal stress value
Vertical principal stress value varies with depth	True	If True, Vertical principal stress value varies with depth and the horizontal principal stress value also changes with depth simultaneously
Turnning depth	5000 m	If Vertical principal stress value varies with depth is true, starting at this depth, the stress no longer changes with depth
Shear traction solved from stress tensor	False	If 'True', the non-uniform shear stress is projected onto the non-planar fault surface by the stress tensor
Rake solved from stress tensor	False	If 'True', the non-uniform rakes are solved from the stress tensor.
Fix_rake	30°	If 'True', Set fixed rakes if 'Rake solved from stress tensor' is 'False'.
Widths of VS region	5000 m	The width of the VS region near boundary.
Widths of surface VS region	2000 m	Widths of VS region near free surface
Transition region from VS to VW region	3000 m	Transition region width from VS to VW region

method. It outputs the maximum slip rate, current time step size, and related parameters, while also beginning to save the simulation results.

The file output including cell information, the slip and slip rate distribution, stress and state etc are exported in the .vtk format in `outputvtk` directory , which is a standard 3-D geometry format that can be read with such visualization tools as Paraview (<http://www.paraview.org>). We performed a 200-year simulation of a frictionally heterogeneous fault model using over 350,000 time steps (Figure 5). Computations were carried out in parallel using MPI on 14 cores of a 12th Gen Intel® Core™ i9-12900K processor, requiring approximately 10 days. The model contains more than 240,000 boundary elements and consumed over 60 GB of memory during execution. With a uniform cell size of 120 m, the critical nucleation size and cohesive zone length within the VW patches are approximately 1773 m and 374 m, respectively, allowing accurate simulation of events down to M_w 4.6 (Figure 4b). PyQuake3D successfully captures a broad range of fault behaviors, including the progressive buildup and abrupt release of shear stress (Figure 5h); aseismic creep and afterslip; episodic slow-slip events without seismic

Table 4: Nucleation and Friction Setting

Parameter	Default	Description
Set_nucleation	False	If True, sets a patch whose shear stress and sliding rate are significantly greater than the surrounding area to meet the nucleation requirements.
Radius of nucleation	8000 m	The radius of the nucleation region
Nuclea_posx	34000 m	Posx of Nucleation
Nuclea_posy	15000 m	Posy of Nucleation
Nuclea_posz	-15000 m	Posz of Nucleation
Rate-and-state parameters a in VS region	0.04	Rate-and-state parameters a in VS region
Rate-and-state parameters b in VS region	0.03	Rate-and-state parameters a in VS region
Characteristic slip distance in VS region	0.13 m	Characteristic slip distance in VS region
Rate-and-state parameters a in VW region	0.004	Rate-and-state parameters a in VW region
Rate-and-state parameters a in VW region	0.03	Rate-and-state parameters a in VW region
Characteristic slip distance in VW region	0.13 m	Characteristic slip distance in VW region
Rate-and-state parameters a in nucleation region	0.004	Rate-and-state parameters a in nucleation region
Rate-and-state parameters a in nucleation region	0.03	Rate-and-state parameters a in nucleation region
Characteristic slip distance in nucleation region	0.14 m	Characteristic slip distance in nucleation region
Initial slip rate in nucleation region	3e-2	Initial slip rate in nucleation region
Changefria	False	If True, a changes gradually b remains unchanged, vice versa
Initlab	True	If True, setting random non-uniform normal stress

radiation; and recurring microseismic activity surrounding major events. These results highlight the ability of PyQuake3D to model multi-scale interactions between seismic and aseismic slip in geologically motivated settings.

Table 5: Output Setting

Parameter	Default	Description
totaloutputsteps	2000	The number of calculating time steps.
outsteps	50	The time step interval for outputting the VTK files.
outputSLIPV	False	If True, output slip rate for each step.
outputTt	False	If True, output shear stress for each step.
outputstv	True	If True, the VTK files will be saved in outvtk directroy.
outputmatrix	False	If True, the matrix format txt files will be saved in out directroy.

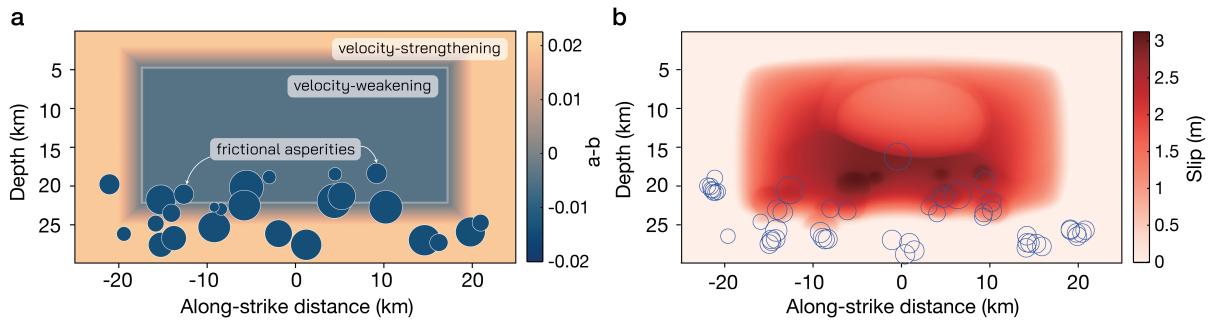


Figure 4: Frictional heterogeneity and rupture behavior in the fault model. (a) Initial distribution of the friction parameter $a-b$, with a central velocity-weakening region bounded by a velocity-strengthening margin. Dark blue circles mark strongly velocity-weakening patches representing small-scale asperities. (b) Coseismic slip distribution during the first dynamic rupture, followed by the first slow slip event. Blue circles indicate all simulated microseismic events over the 200-year period.

```

1 #Files
2 #Files
3 Corefunc directory: planar10w
4 save Corefunc: False
5
6 Hmatrix_mpi_plot:True
7 Node_order: False
8 Scale_km: True
9
10 #Property
11 Lame constants: 32038120320.0
12 Shear modulus: 32038120320.0
13 Rock density: 2670
14 InputHetoparamter: True
15 Inputparamter file: initcondion.txt
16
17 #Stress
18 Half space: True
19 Fix_Tn:True
20 Vertical principal stress: 1.0
21 Maximum horizontal principal stress: 1.6
22 Minimum horizontal principal stress: 0.6
23 Angle between ssh1 and X-axis: 90
24 Vertical principal stress value: 50
25 Vertical principal stress value varies with depth: True
26 Turnning depth: 5000
27 Normal traction solved from stress tensor: False
28 Shear traction solved from stress tensor: False
29 Rake solved from stress tensor: False
30 Fix_rake: 0
31 Widths of VS region: 5000
32 Widths of surface VS region: 2000

```

```

33 Transition region from VS to VW region: 3000
34
35
36 #Friction
37 Reference slip rate: 1e-6
38 Reference friction coefficient: 0.6
39 Rate-and-state parameters a in VS region: 0.0185
40 Rate-and-state parameters b in VS region: 0.001
41 Characteristic slip distance in VS region: 0.015
42 Rate-and-state parameters a in VW region: 0.0185
43 Rate-and-state parameters b in VW region: 0.024
44 Characteristic slip distance in VW region: 0.015
45 Rate-and-state parameters a in nucleation region: 0.01
46 Rate-and-state parameters b in nucleation region: 0.0185
47 Characteristic slip distance in nucleation region: 0.004
48 Initial slip rate in nucleation region: 3e-2
49 Plate loading rate: 1e-9
50 ChangefriA:False
51 Initlab: False
52
53 #nucleartion
54 Set_nucleation: False
55 Nuclea_posx: 34000
56 Nuclea_posy: 15000
57 Nuclea_posz: -15000
58 Radius of nucleation: 8000
59
60 #output
61 outputSLIPV: False
62 outputTt: False
63 totaloutputsteps: 1000
64 outsteps: 200
65 outputvtk: True
66 outputmatrix: False

```

Listing 1: Input of Heterogeneous frictional model

```

1 # -----
2 # PyQuake3D: Boundary Element Method to simulate sequences of earthquakes and aseismic
   slips
3 # * 3D non-planar quasi-dynamic earthquake cycle simulations
4 # * Support for Hierarchical matrix storage and calculation
5 # * Parallelized with MPI (12 cpus)
6 # * Support for rate-and-state aging friction laws
7 # * Supports output to VTK formats
8 # *
9 Cs 3464.0
10 First Lame constants 32038120320.0
11 Shear Modulus 32038120320.0
12 Youngs Modulus 80095300800.0
13 Poissons ratio 0.25
14 a,b,L: 0.01 0.025 0.001
15 maximum element size 161.5330463540536
16 average elesize 120.13229265066029
17 Critical nucleation size 118.21362089765466
18 Cohesive zone: 23.938258231775073
19 Start calculating Hmatrix...
20 Worker 0 receive the task result 1407, size = (32, 30)
21 Master: Worker 3 finish task 1407 , size = (32, 30)
22 Master: complete 1397/ 213580
23 Master: assign task 1408 to Worker 3, size = (25, 28)
24 [Worker 3] waiting for task...
25 rank 3,start fullmatrix calc...
26 rank 3,Full matrix calculation task success,size(25, 28),Time takes 0.0179865360 seconds
27 Worker 3 send the the task result 1408, size = (25, 28)
28 [Worker 3] waiting for task...
29 Worker 0 receive the task result 1408, size = (25, 28)
30 Master: Worker 3 finish task 1408 , size = (25, 28)
31 Master: complete 1398/ 213580
32 Master: assign task 1409 to Worker 3, size = (25, 30)
33 rank 3,start fullmatrix calc...
34 rank 3,Full matrix calculation task success,size(25, 30),Time takes 0.0158853531 seconds
35 Worker 3 send the the task result 1409, size = (25, 30)

```

```

36 Worker 0 receive the task result 1409, size = (25, 30)
37 Master: Worker 3 finish task 1409 , size = (25, 30)
38 Master: complete 1399/ 213580
39 Master: assign task 1410 to Worker 3, size = (112, 114)
40 [Worker 3] waiting for task...
41 rank 3,start ACA...
42 rank 8,ACA of task success,size(476, 465),Time takes 2.8612349033 seconds
43 Worker 8 send the the task result 1375, size = (476, 465)
44 [Worker 8] waiting for task...
45 iteration: 0
46 dt: 0.001 max_vel: 9.99999717199876e-10 Seconds: 0.001 Days: 1.1574074074074074e-08
      year 3.1709791983764586e-11
47 iteration: 20
48 dt: 3.3252567300796505 max_vel: 9.99999715603074e-10 Seconds: 9.973770190238952
      Days: 0.00011543715497961749 year 3.162661780263493e-07
49 iteration: 40
50 dt: 11057.332320940008 max_vel: 9.999994415927274e-10 Seconds: 33171.99496282003
      Days: 0.38393512688449105 year 0.0010518770599575098
51 iteration: 60
52 dt: 903248.7103340095 max_vel: 9.999207208431887e-10 Seconds: 8690287.646132415 Days
      : 100.58203294134739 year 0.27556721353793806
53 iteration: 80
54 dt: 607203.8217271981 max_vel: 1.0574466703090563e-09 Seconds: 30915432.66035066
      Days: 357.8175076429475 year 0.9803219387478013

```

Listing 2: State output of HF-model during program execution

9 Stop Control

The simulation stops when any of the following is satisfied.

- The time-step reaches the *totaloutputsteps*.
- RungeKutta_solve_Dormand_Prince iteration attempted 20 times without meeting the error tolerance requirements.

10 Visualization

The current program supports output in VTK format and numpy, and the vtk can be used for 3D visualization in ParaView. We encourage users to develop their own code within the main function to flexibly output data using sim0 object from QDsim class. The sim0 object contains all variables required for the simulation, and you can access them by using sim0.variables.

11 License

This project is licensed under the MIT License.

12 Acknowledgments

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introduced in:

Ozawa, S., Ida, A., Hoshino, T., & Ando, R. (2023). Large-scale earthquake sequence simulations on 3-D non-planar faults using the boundary element method accelerated by lattice H-matrices. *Geophysical Journal International*, 232(3), 1471–1481.

The implementation of the stress Green's functions builds on the MATLAB routines from:

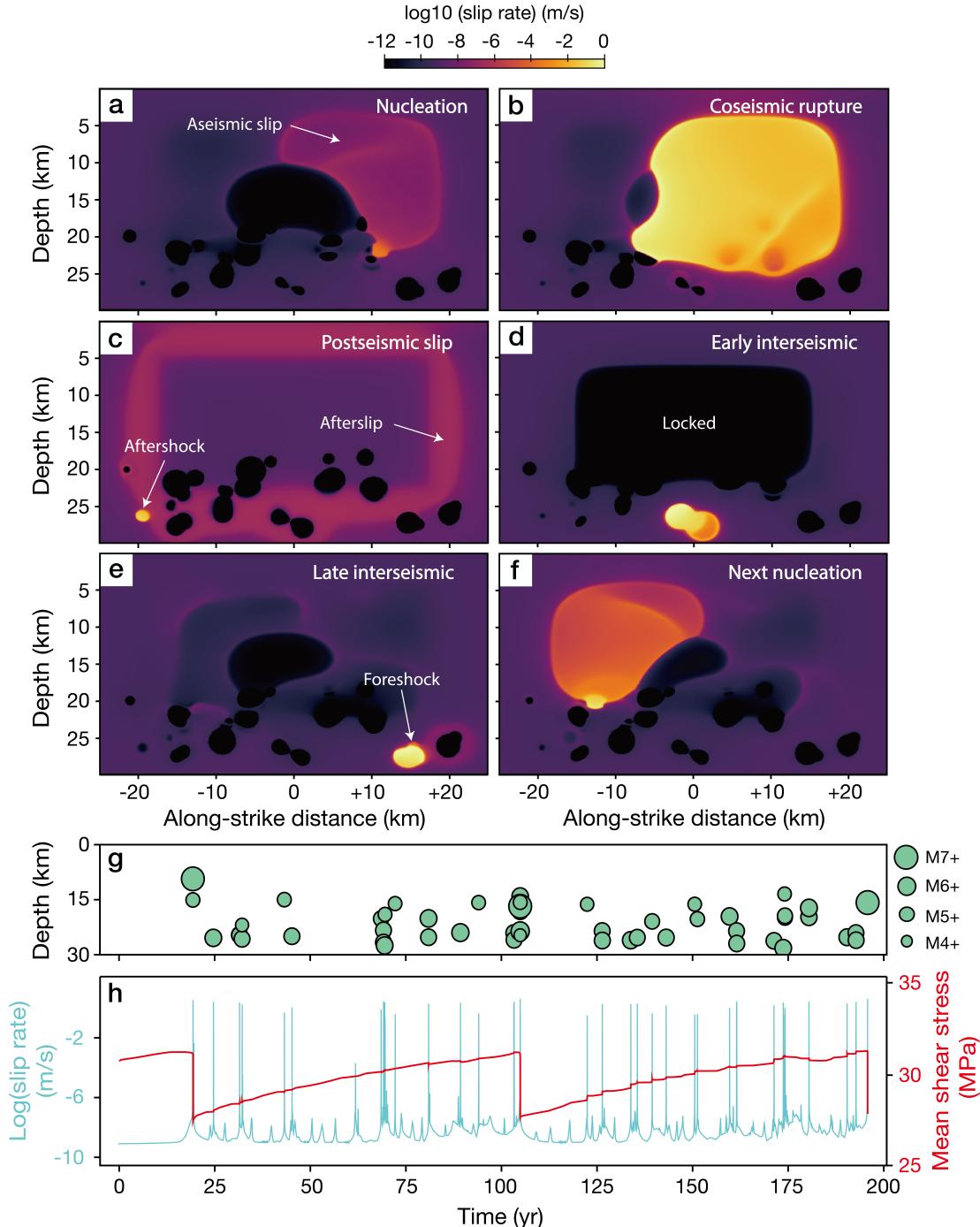


Figure 5: Spatiotemporal variations in slip rate and seismicity in the frictionally heterogeneous model. Panels (a–f) show slip rate evolution during key phases of the seismic cycle. (g) Spatiotemporal variations in event locations and magnitudes. (h) Time evolution of maximum slip rate and average shear stress.

Nikkhoo, M., & Walter, T. R. (2015). Triangular dislocation: an analytical, artefact-free solution. *Geophysical Journal International*, 201(2), 1119–1141.

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