

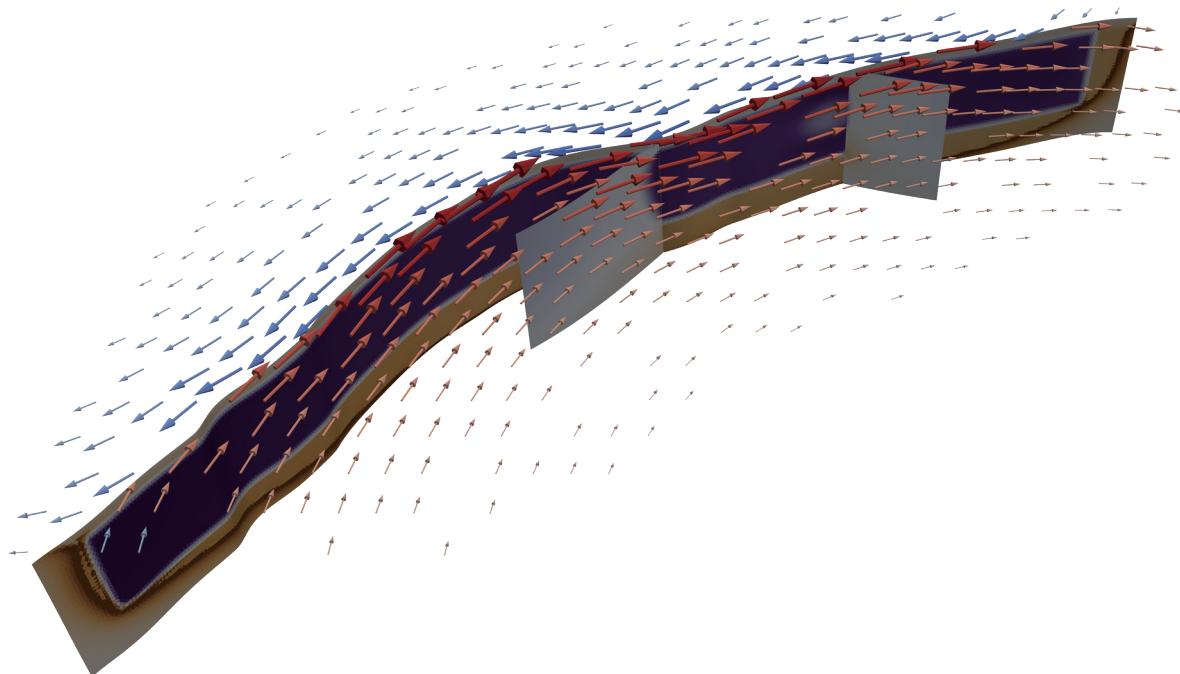


PyQuake3D

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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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 can couple the boundary element governing equation and the finite difference fluid pore pressure diffusion equation, thus support for pore pressure varying with slip due to inelastic processes including dilatancy and pore compaction.

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 for Quasi-dynamic Model

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]:

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

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

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

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

$$\frac{d\tau_{2,i}}{dt} = \left(1 + \frac{\mu}{2c_s} \frac{\partial V_{2,i}}{\partial \tau_{2,i}} \right)^{-1} \left[- \sum_{j=1}^N k_{ij}^{s2} V_{2,j} + \dot{\tau}_{2,i} - \frac{\mu}{2c_s} \left(\frac{\partial V_{2,i}}{\partial \sigma_i} \frac{d\sigma_i}{dt} + \frac{\partial V_{2,i}}{\partial \psi_i} \frac{d\psi_i}{dt} \right) \right] \quad (13)$$

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:

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

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

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

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

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

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 $\frac{\epsilon_0}{\epsilon_k}$ is less than 1.0. 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.

To ensure numerical resolution of rupture, we monitor two key physical length scales. The first is the process zone size Λ , given by:

$$\Lambda = C \frac{\mu d_c}{b \sigma_n} \quad (28)$$

which characterizes the breakdown zone near the rupture front. The constant C is equal to $9\pi/32$ given by Lapusta and Liu [2009]. Three-dimensional dynamic rupture simulations by Day et al. [2005] demonstrated that a resolution of at least $\Lambda/\Delta x = 3\text{--}5$ is required to adequately capture the physical features of rupture propagation. Figure ??b shows a snapshot of the resulting shear stress field, with localized gradients near the VW/VS interface consistent with this scale. The second critical length scale is the nucleation size h^* , defined as [Rice and Ruina, 1983, Rubin and Ampuero, 2005, Chen and Lapusta, 2009]:

$$h^* = \frac{\pi}{2} \cdot \frac{\mu b d_c}{(b-a)^2 \sigma_n} \quad (29)$$

This scale governs the minimum size of the VW patch required for spontaneous nucleation. These two length scales (Λ , h^*) must be appropriately resolved by the mesh to ensure physically meaningful and numerically stable earthquake cycle simulations.

3.2 Dilatancy Law

We model earthquake cycles with 3-D elasticity, rate-state friction, and a dilatancy law where porosity evolves toward steady state over distance d_c , using BIEM coupled with Finite Difference Method (FDM). Following [Segall and Rice, 1995] and [Segall et al., 2010], we assume a constitutive equation for the inelastic change in porosity $\delta\phi$, including both dilatancy and compaction. We associate dilatancy/compaction with changes in the average lifetime of asperity contacts within the fault gouge, such that

$$\delta\phi = -\epsilon \ln \left(\frac{V_0\theta}{c} \right) \quad (30)$$

$$\frac{d\phi}{dt} = -\epsilon \frac{d}{dt} \ln \left(\frac{V_0\theta}{c} \right) = -\epsilon \frac{d\theta}{dt} \quad (31)$$

Where ϵ is an empirically derived constant of order 10^{-4} , based on [Marone et al., 1990] experiments. Above steady state, that is for $\theta > d_c/V$, θ decreases (from 6), and the gouge dilates, while below steady state, θ increases and the gouge compacts.

To investigate the role of dilatancy in earthquake cycles we consider coupled friction, dilatancy and pore fluid flow. We consider homogeneous diffusion model which accurately models fault-normal flow with diffusivity C_{hyd} . We assume dilatancy greatly dominates effects of temperature T and pore pressure p variation on porosity change within the thin shearing layer h . Neglecting pore fluid flow parallel to the fault, for the same reason that heat flow in this direction is negligible, changes in pore pressure in the rock surrounding the shear zone is given by [Segall et al., 2010] and [Segall and Rice, 2006]

$$\frac{\partial p}{\partial t} = c_{hyd} \frac{\partial^2 p}{\partial y^2} + \Lambda \frac{\partial T}{\partial t}; \quad \left. \frac{\partial p}{\partial y} \right|_{y=0^+} = \frac{(1-\phi)\dot{h}}{2\beta c_{hyd}} = \frac{h\dot{\phi}}{2\beta c_{hyd}} \quad (32)$$

Where hydraulic diffusivity $C_{hyd} = \kappa/\eta\beta$, κ is the permeability, η is pore fluid viscosity and β is compressibility of the fluid and the pore space. Λ is the thermal pressurization parameter, equal to the ratio of thermal expansivity to compressibility. In the current version of PyQuake3D, we ignore the temperature requirement, such a simplified diffusion equation yeild

$$\frac{\partial p}{\partial t} = c_{hyd} \frac{\partial^2 p}{\partial y^2}; \quad \left. \frac{\partial p}{\partial y} \right|_{y=0^+} = \frac{h\dot{\phi}}{2\beta c_{hyd}} \quad (33)$$

3.3 Coupled solution of friction mechanics and diffusion equation using BIEM and FDM

The coupling between the frictional relation and pore pressure is incorporated by modifying Equation 8 as

$$\frac{\tau_i}{\sigma_i - p} = a \arcsin(h) \left(\frac{V_i}{2V_0} \exp \left(\frac{\psi_i}{a} \right) \right) \quad (34)$$

Accordingly, the chain rule must be corrected to

$$\frac{dV_i}{dt} = \frac{\partial V_i}{\partial \tau_i} \frac{d\tau_i}{dt} + \frac{\partial V_i}{\partial \sigma_i} \frac{d\sigma_i}{dt} + \frac{\partial V_i}{\partial \psi_i} \frac{d\psi_i}{dt} + \frac{\partial V_i}{\partial p_i} \frac{dp_i}{dt} \quad (35)$$

With this modification, the corresponding Equation 11 becomes

$$\frac{d\tau_i}{dt} = \left(1 + \frac{\mu}{2c_s} \frac{\partial V_i}{\partial \tau_i} \right)^{-1} \left[- \sum_{j=1}^N k_{ij}^s V_j + \dot{\tau}_i - \frac{\mu}{2c_s} \left(\frac{\partial V_i}{\partial \sigma_i} \left(\frac{d\sigma_i}{dt} - \frac{dp_i}{dt} \right) + \frac{\partial V_i}{\partial \psi_i} \frac{d\psi_i}{dt} \right) \right] \quad (36)$$

The Equation 12 and 13 should be revised in the same manner. Furthermore, in Equations 14 to 19 , the normal stress σ must be replaced by the effective normal stress $\sigma - p$.

The problem now becomes solving the ordinary differential equations system 4, 9, modified 12 and 13 , as well as the diffusion Equation 33. The first four differential equations are still solved using the Runge-Kutta method, which interacts with the diffusion equation through p and dp/dt , while the diffusion equation is solved using finite difference method, which interacts with the friction mechanics through state variable (Equation 31). Then multi-physics coupling is ultimately solved iteratively using the partitioned Approach.

Near the fault it is important that the discretization be sufficiently fine to capture the steep gradient in p . To achieve this we make the following change of coordinate between y and z .

$$z(y) = \ln(1 + y/c) \quad (37)$$

Where y is fault normal distance. This change of coordinate has the effect of making the mesh near the fault and sparse near $y = y_\infty$. y_∞ is set to be the distance 10 m far away from the fault plane and has background pore pressure. The constant c is set to 10^{-2} to yield good results.

Following the change of coordinate, the system of equations 33 is converted to [Segall et al., 2010]

$$\dot{p} = c_{hyd} e^{-z} (e^{-z} p_z)_z \quad \text{on } y > 0 \quad (38)$$

$$e^{-z} p_z = g \quad \text{on } y = 0 \quad (39)$$

$$p = p_\infty \quad \text{on } y = y_\infty. \quad (40)$$

We discretize the PDE and boundary conditions 38 in space, letting $\delta = \Delta z/2$

$$\dot{p}_k = c_{hyd} e^{-z_k} \times \left(\frac{-e^{-(z_k-\delta)}(p_k - p_{k-1}) + e^{-(z_k+\delta)}(p_{k+1} - p_k)}{\Delta z^2} \right) \quad (41)$$

$$e^{-z_0} \frac{p_1 - p_{-1}}{2\Delta z} = g \quad \text{on } y = 0 \quad (42)$$

$$p_K = p_\infty \quad \text{on } y = y_\infty \quad (43)$$

for $k = 0, 1, \dots, K$. The discretization 38 is a second-order-accurate conservative discretization of the gradient of the flux function $e^{-z} p_z$ in 38. The discretization of the Neumann boundary condition 42 is a second-order-accurate approximation centered around $k = 0$. Note that the ghost variable p_{-1} is eliminated when 42 is introduced into 41.

We next consider the method for time stepping the system of equations. Let p_{km}^n be the value of p at the k th point in the y direction and the m th point in the x direction, at the n th time step. For simplicity in presentation we illustrate the time stepping procedure for the spatially uniform, rather than log discretization. Equations 38 and 39 are discretized in time as:

$$\frac{p_{km}^{n+1} - p_{km}^n}{\Delta t} = c_{hyd} \left(\frac{p_{(k-1)m}^{n+1} - 2p_{km}^{n+1} + p_{(k+1)m}^{n+1}}{\Delta y^2} \right) \quad (44)$$

$$\frac{p_{1m}^{n+1} - p_{(-1)m}^{n+1}}{2\Delta y} = g(u_m^{n+1}) \quad \text{and} \quad p_{Km}^{n+1} = p_\infty \quad (45)$$

where $m = 1, \dots, M$ and $k = 1, \dots, K$. Note that the equations for p are implicit in that pore pressure at time step $n+1$ depends on p^{n+1} . An important feature is that for each position along the fault (indexed

by m), the pore pressure along the fault normal profile depends only on the quantities at index m . Thus, the pore pressures on the fault are only coupled through the friction/elasticity equations. Thus, the finite difference computations along the fault decouple, such that M small systems of equations (with K elements) are solved at each time step using MPI, rather than one very large system of equations. This is vastly more efficient than solving the full implicit equations.

3.4 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.

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

```

3.6 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

$$\min\{\text{diam}(Q_\tau), \text{diam}(Q_\sigma)\} \leq \eta \text{dist}(Q_\tau, Q_\sigma) \tag{46}$$

We can compute the diameters and distances of the boxes by

$$\text{diam}(Q_\tau) = \left(\sum_{k=1}^d (b_{\tau,k} - a_{\tau,k})^2 \right)^{1/2} \quad \text{and} \tag{47}$$

$$\text{dist}(Q_\tau, Q_\sigma) = \left(\sum_{k=1}^d (\max(0, a_{\tau,k} - b_{\sigma,k})^2 + \max(0, a_{\sigma,k} - b_{\tau,k})^2) \right)^{1/2}. \tag{48}$$

3.7 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.

3.8 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).

3.9 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

$$\vec{e}_3 = \vec{v}_{ab} \times \vec{v}_{ac} \quad (49)$$

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

$$\begin{aligned} e_{11} &= e_{32} \\ e_{12} &= -e_{31} \\ e_{13} &= 0 \end{aligned} \quad (50)$$

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

$$\vec{e}_2 = \vec{e}_3 \times \vec{e}_1 \quad (51)$$

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.

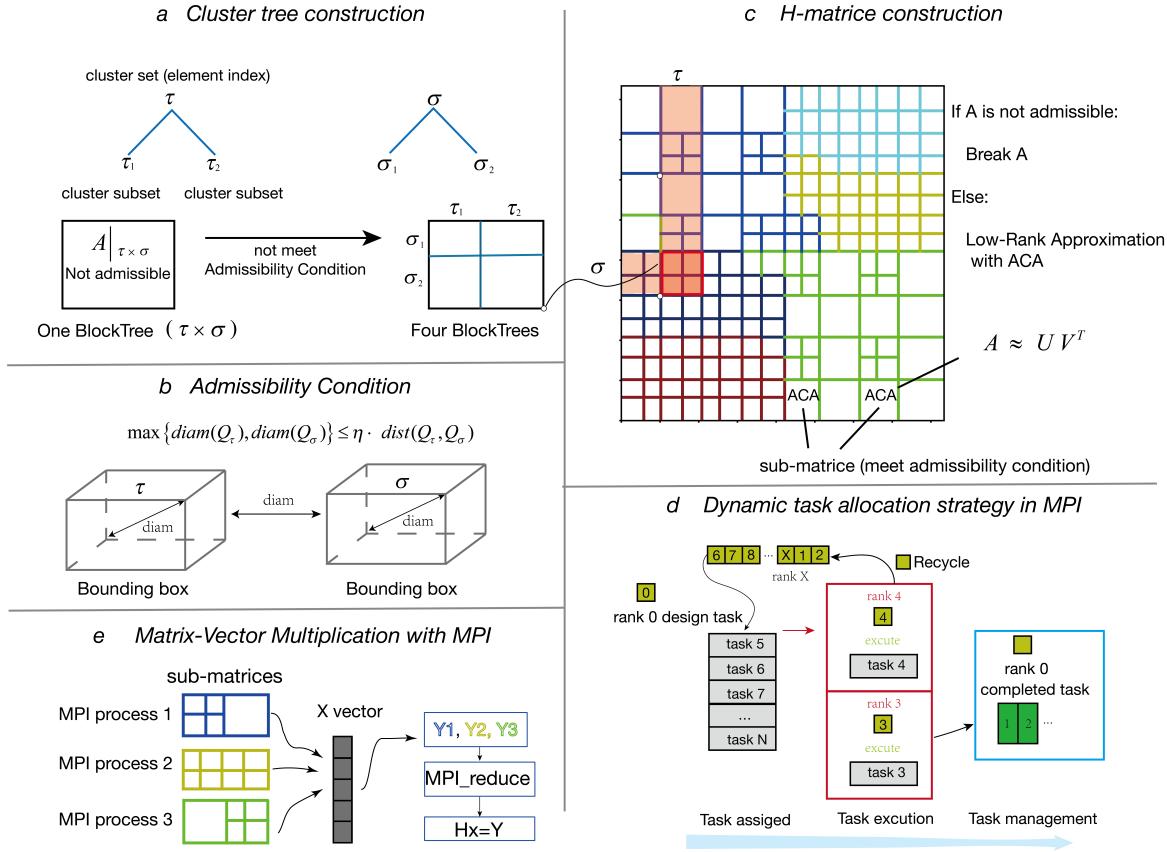


Figure 1: Construction of hierarchical matrix speed up by MPI

3.10 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.

$$\begin{bmatrix} e_{11} & e_{21} & e_{31} \\ e_{12} & e_{22} & e_{32} \\ e_{13} & e_{23} & e_{33} \end{bmatrix} \begin{bmatrix} x_1 \\ x_2 \\ x_3 \end{bmatrix} = \begin{bmatrix} X_1 \\ X_2 \\ X_3 \end{bmatrix} \quad (52)$$

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

4 Code Availability and Installation

The **PyQuake3D** code is openly available at <https://github.com/Computational-Geophysics/PyQuake3D>, and we recommend installing it within a conda environment. If you are not familiar with conda, we provide a step-by-step guide to installing at https://github.com/Computational-Geophysics/PyQuake3D/blob/main/tutorials/QD_low_resolution/tutorial_BP5.ipynb, which cover installation, compilation, setup, and running a simple simulation. We also describe the details in Section 5.5.

4.1 python Requirements

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

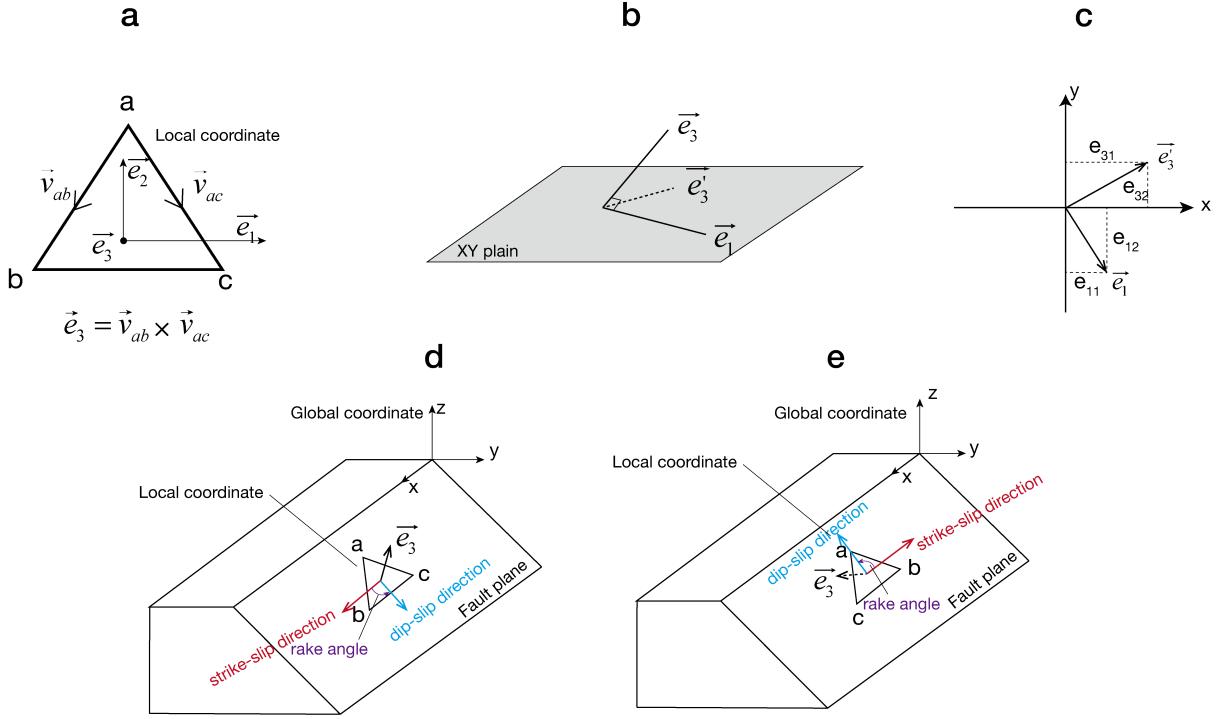


Figure 2: Definition of strike-slip and dip-slip direction. (a) Calculation of normal vector or z-vector in element local coordinate system \vec{e}_3 . (b) Projection of \vec{e}_3 on XY plane \vec{e}_3' . (c) Conversion between \vec{e}_3' and \vec{e}_1 . (d) Looking from the negative direction of the z-axis, the unit nodes are counterclockwise, and the element normal is outwards. The strike-slip direction is defined as the positive x direction, and the y direction can be obtained by cross-producing the z and x unit vectors. (e) Looking from the negative direction of the z-axis, the unit nodes are clockwise, and the element normal is inwards. The strike-slip direction is defined as the negative x direction.

Package
python≥ 3.8
numPy
psutil
matplotlib
sciPy
joblib
mpi4py
imageio
h5py
joblib
pyvista

Table 1: Required dependencies for running PyQuake3D.

Notes: PyQuake3D supports Python 3.8 and above, so there is no need to specify a version when installing the library. To install all required dependencies, simply run:

```
pip install -r requirements.txt
```

Or use conda to install at root directory:

```
conda env update -f environment.yml
```

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

Install `cupy` if you want to use GPU acceleration, we recommended to use `conda` in prompt terminal (e.g. CUDA 11.8):

```
conda install -c conda-forge cupy cudatoolkit=11.8
```

Notes: CuPy relies on NVIDIA CUDA for GPU computing, so the following components are required:

1. NVIDIA GPU Driver: Ensure your system has a CUDA-capable NVIDIA GPU (check compatibility at <https://developer.nvidia.com/cuda-gpus>). The driver version must support the CUDA Toolkit version used by CuPy (e.g., CUDA 10.2–12.x for CuPy v13.x).

2. CUDA Toolkit: CuPy supports specific CUDA versions (check the latest compatibility at <https://docs.cupy.dev/en/stable/>). Common versions: CUDA 11.8 or 12.2 are widely used.

4.2 C++ Requirements

The `TDstressFS_C.cpp` in folder `src` is a C++ source file that computes full-space and half-space Green's functions, translated from the Python script `TDstressFS.py` and `TDstressHS.py` to leverage C++'s performance for efficient numerical calculations. It is compiled into a dynamic library, `TDstressFS_C.so`, using a provided `Makefile`, which must be executed with the `make` command before running the code to ensure compatibility across different computing environments. The generated library is called by the Python script `Hmatrix.py` via dynamic loading (e.g., using `ctypes`). To use it, navigate to the code directory `src`, run `make` to build `TDstressFS_C.so`.

To make `.so` file and implement MPI in Linux system, install `g++` compiler (including `gcc` and other related tools) are needed. Common options are:

- `sudo apt update`
- `sudo apt install g++`
- `sudo apt install openmpi-bin libopenmpi-dev`

5 How to run PyQuake3D

To get started, clone the PyQuake3D repository from GitHub:

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

5.1 Usage Modes

PyQuake3D supports two execution backends:

- **single CPU/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 calculations.
- **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.

PyQuake3D can be executed either in single CPU/GPU mode (`main_gpu.py`) or in MPI-parallel mode (`main_mpi.py`), depending on the size of your model. All simulations are launched from the project's root directory using the `main_gpu.py` and `main_mpi.py` script located in the `src` folder.

5.2 Standard Execution (single GPU/CPU)

To run a simulation using the standard execution mode (with optional GPU acceleration), use the following command in the PyQuake3D root directory:

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

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

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

Ensure you modify the input parameter (`parameter.txt`) as follows:

- InputHetoparamter: True
- Inputparamter file: bp5tparam.dat

5.3 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_mpi.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.

5.4 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.

5.5 Step by step to run a simple case

We provides a step-by-step guide to use **PyQuake3D**. We'll cover installation, compilation, setup, and running a simple simulation.

5.5.1 Standard Execution single GPU/CPU version on Windows

Step 1: Set Up Conda environment

1. Download from <https://www.anaconda.com/docs/getting-started/miniconda/install>
2. Then install it using exe program.
3. Open miniconda Prompt and navigate to the working directory(e.g. E:\work) using: E: then cd E:\work
4. After installation, create a new environment: conda create -n PyQuake3D python=3.12
5. Activate the environment: conda activate PyQuake3D
6. Install Jupyter notebook using: conda install jupyter notebook

Step 2: Install Python Dependencies

1. Download from <https://github.com/Computational-Geophysics/PyQuake3D>
2. Install PyQuake3D in conda Prompt using pip:


```
pip install -r requirements.txt
```

 or


```
python -m pip install -r requirements.txt
```

 or


```
conda env update -f environment.yml
```

 (make sure PyQuake3D environment is activated)

Notes:PyQuake3D supports Python 3.8 and above, so there is no need to specify a specific version when installing the library.

Step 3: Runging a simple case

The easiest way to run pyquake3d is to run the single CPU version of Pyquake3D, without installing cupy. **Here we provide a BP5-QD simulation with low resolution, with initial paremeters being set up in parameter.txt.** The procedures are follows:

1. Read model and mesh parameter(Please refer to mannul for specific meaning).
2. Calculating Green functions.
3. Calculating Quasi-Dynamic model.
4. Visualize the results.

You can also run the BP5-QD example case in the terminal:

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

Initial: Import all sub-functions and libraries

```

1 #Let runing PyQuake3D
2 #First Import all sub-functions
3
4 import readmsh
5 import numpy as np
6 import sys
7 import matplotlib.pyplot as plt
8 import QDsim_gpu
9 from math import *
10 import time
11 import argparse
12 import os
13 import psutil
14 from datetime import datetime
15 process = psutil.Process(os.getpid())

```

Listing 1: Import all sub-functions and libraries

Step 1: read the model file, parameter file, and create a basic class

```

1 fnamegeo='BP5_3k/bp5t.msh'
2 fnamePara='BP5_3k/parameter.txt'
3 nodelst,eelst=readmsh.read_mshV2(fnamegeo)

```

Listing 2: read the model

Create mesh model through Gmesh

You can create your own mesh model through Gmesh, download from <https://gmsh.info/>. You can download the latest version, but remember to use version 2 when exporting mesh model. First you need to prepare .geo file, and open it using Gmesh and it automatically mesh the domain. Then export .msh file by *File->export->Inputbp5.msh->Version2ASCII*).

A simple asperity_circle.geo format and notes are as follows:

```

1 // Parameters
2 angle = 25;      // Dip angle of the fault in degrees
3 Len = 100;       // Fault length along x-axis
4 width = 40;      // Fault width along z-axis
5 lc = 1.5;        // Characteristic length for mesh cell size
6
7 // Define points for the rectangular fault plane
8 Point(1) = {-Len/2, 0, 0, lc}; // Bottom-left corner (A)
9 Point(2) = {Len/2, 0, 0, lc}; // Bottom-right corner (B)
10 Point(3) = {Len/2, 0, -width, lc}; // Top-right corner (C)
11 Point(4) = {-Len/2, 0, -width, lc}; // Top-left corner (D)
12
13 // Alternative points for a dipping fault (commented out)
14 //Point(3) = {Len/2, width * Cos(angle * Pi / 180), -width * Sin(angle * Pi / 180), lc};
15 //Point(4) = {-Len/2, width * Cos(angle * Pi / 180), -width * Sin(angle * Pi / 180), lc
16 //};
17
18 // Define lines connecting the points
19 Line(1) = {1, 2}; // Line from A to B (bottom edge)
20 Line(2) = {2, 3}; // Line from B to C (right edge)
21 Line(3) = {3, 4}; // Line from C to D (top edge)
22 Line(4) = {4, 1}; // Line from D to A (left edge)
23
24 // Define the surface by creating a line loop and plane
25 Line Loop(1) = {1, 2, 3, 4}; // Closed loop of lines A-B-C-D
26 Plane Surface(1) = {1}; // Create a planar surface from the line loop
27
28 // Mesh generation settings
29 //Mesh.Algorithm = 1; // Delaunay triangulation
30 //Mesh.Algorithm = 8; // Structured quadrilateral mesh
31 //Mesh.ElementOrder = 1; // Use first-order
32 //Mesh.RecombineAll = 1; // Recombine triangles
33
34 // Generate the 2D mesh
35 Mesh 2;

```

```

35 // Save the mesh to a file
36 Mesh.Format = 2;           // Output format: 1 = MSH1 format (Gmsh legacy format)
37 //Save "fault_mesh.msh";   // Save the mesh as fault_mesh.msh
38

```

Listing 3: A simple asperity_circle.geo file

Create parameter and external input file

The parameter.txt file serves as a configuration file for the simulation, defining all necessary parameters to control the execution of the model. It organizes input data into distinct sections for clarity and modularity, including:

1. **Files and Cells:** Specifies file paths and mesh cell size settings.
2. **Property:** Defines material properties of the fault, such as elastic moduli or density.
3. **Fluid:** Configures fluid-related parameters, like Dilatancy coefficient or pore pressure.
4. **Stress:** Sets stress conditions applied to the fault, such as normal or shear stress.
5. **Friction:** Describes frictional properties, including friction coefficients or laws.
6. **Nucleation:** Defines parameters for initiating fault slip, such as nucleation zone size or critical stress.
7. **Output:** Configures output settings, including data formats and variables to save.

If external data is imported as the initial model, just set **InputHetoparamter: True**, and stress and friction parameters can be ignored.

Note: Please refer to section 7 for a detailed explanation of each parameter. The order of all parameters in parameter.txt can be arbitrarily disrupted, but the parameter names must remain strictly unchanged.

Visualize mesh model using PyQuake3D

All initial parameters are easily accessible through class member variables.

```

1 #Establish the initial model and generate simulation class
2 sim0=QDsim_gpu.QDsim(elelst,nodelst,fnamePara,calc_greenfunc=False)
3 #Ouput initial state
4 fname='Init.vtk'
5 sim0.ouputVTK(fname)
6
7 import pyvista as pv
8 plotter = pv.Plotter(off_screen=True)
9 mesh = pv.read(fname)
10 print(mesh)
11 print(mesh.cell_data)
12 variab = 'a-b' #choose the arrays to display
13
14 scalar_bar_args={
15     'title': variab,
16     'position_x': 0.22,
17     'position_y': 0.85,
18 }
19 plotter.add_mesh(mesh, scalars=variab, show_edges=True,scalar_bar_args=scalar_bar_args)
20     # show shear stress
21 plotter.show(cpos='xz')

```

Listing 4: Visualize mesh model

output:

Step 3: Calculating Qusi-Dynamic model by loop

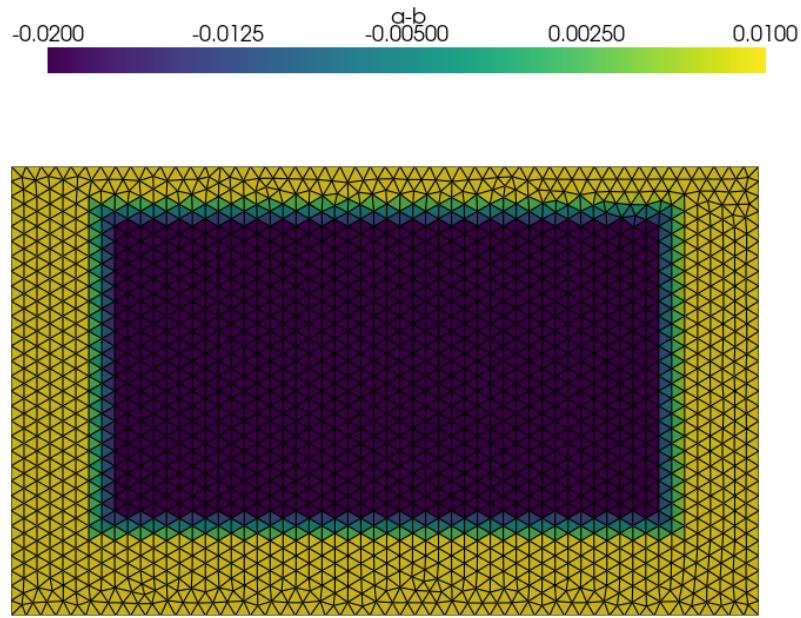


Figure 3: mesh model and spatial distribution of a-b.

```

1 start_time=time.time()
2
3 totaloutputsteps=int(sim0.Para0['totaloutputsteps'])
4 directory='outvtk'
5 if not os.path.exists(directory):
6     os.mkdir(directory)
7
8 f=open('state.txt','w')
9 f.write('iteration time_step(s) maximum_slip1_rate(m/s) maximum_slip2_rate(m/s) time(s)\n')
10
11 if(sim0.useGPU==False): #CPU case
12     for i in range(totaloutputsteps):
13
14         if(i==0):
15             dttry=sim0.htry
16         else:
17             dttry=dtnext
18             dttry,dtnext=sim0.simu_forward(dttry)
19             year=sim0.time/3600/24/365
20             if(i%10==0):
21                 print('iteration:',i)
22                 print('dt:',dttry, ' max_vel:',np.max(np.abs(sim0.slipv)), ' Seconds:',sim0.
23                     time, ' Days:',sim0.time/3600/24,
24                     'year',year)
25                 memory_info = process.memory_info()
26                 print(f"Memory usage: {memory_info.rss / (1024 ** 2)} MB")
27                 f.write('%d %f %.16e %.16e %f %f\n' %(i,dttry,np.max(np.abs(sim0.slipv1)),np.max
28                     (np.abs(sim0.slipv2)),sim0.time,sim0.time/3600.0/24.0))

```

```

28
29
30
31     if(sim0.Para0['outputvtk']=='True'):
32         outsteps=int(sim0.Para0['outsteps']) #output steps
33         if(i%outsteps==0):
34             fname=directory+ '/step'+str(i)+'.vtk'
35             sim0.outputVTK(fname)
36
37 end_time = time.time()
38 timetake=end_time-start_time
39 f.write('Program end time: %s\n'%str(datetime.now()))
40 f.write("Time taken: %.2f seconds\n"%timetake)
41
42 print('Program end time: %s\n'%str(datetime.now()))
43 print("Time taken: %.2f seconds\n"%timetake)

```

Listing 5: Calculating Qusi-Dynamic model by loop

Step 4: Visualize Results

The simulation generates VTK files, visualize them using PyVista. You can also output all results in your own format by accessing the member variables of sim0 (e.g. sim0.slip).

```

1 import pyvista as pv
2 import glob
3 import os
4
5 # set vtk file path
6 folder_path = "outvtk/"
7
8 vtk_files = glob.glob(os.path.join(folder_path, "*.vtk")) + glob.glob(os.path.join(
    folder_path, "*.vtu"))
9
10
11 #read state file for time show
12 def is_number(s):
13     try:
14         float(s)
15         return True
16     except ValueError:
17         return False
18
19 def readstate(fname):
20     f=open(fname,'r')
21     K=0
22     data0=[]
23     for line in f:
24         tem=line.split()
25
26         if(len(tem)==6 and is_number(tem[0])==True):
27             data0.append(np.array(tem).astype(float))
28     return np.array(data0)
29 state=readstate('state.txt')
30 print(state.shape)
31
32 # # show one figure
33 plotter = pv.Plotter(off_screen=True)
34 mesh = pv.read(vtk_files[10])
35 slip_velocity = mesh['Slipv[m/s]']
36 # Apply logarithmic transformation (e.g., base 10)
37 # Add small constant (e.g., 1e-10) to avoid log(0) issues
38 log_slip_velocity = np.log10(slip_velocity)
39
40 # Assign the transformed scalars back to the mesh
41 mesh['Log_Slipv[m/s]'] = log_slip_velocity
42 scalar_range = (-12, 0)
43 scalar_bar_args={
44     'title': 'log10(slip rate)[m/s]',
45     'position_x': 0.22,
46     'position_y': 0.85,
47 }

```

```

48 plotter.add_mesh(mesh, scalars='Log_Slipv[m/s]', cmap="plasma", show_edges=True, clim=
49     scalar_range, scalar_bar_args=scalar_bar_args) # show shear stress
50
51 #plotter.camera_position = [(0, -5, 0), (0, 0, 0), (0, 0, 1)]
52 # plotter.add_scalar_bar(
53 #     title='log10(Slip rate)[m/s]', # Label for the colorbar
54 #     position_x=0.25, # Horizontal position (0 to 1, 0.25 centers it with
55 #     width=0.5)
56 #     position_y=0.05, # Vertical position (close to bottom)
57 #     width=0.5, # Width of the colorbar (0 to 1, relative to plot)
58 #     height=0.1, # Height of the colorbar
59 #     vertical=False # Horizontal orientation
60 # )
61 plotter.show(cpos='xz')
62
63 # create animation
64 outsteps=int(sim0.Para0['outsteps'])
65 plotter = pv.Plotter(off_screen=True)
66 plotter.open_gif('animation.gif') # Initialize GIF output
67
68 for i, vtk_file in enumerate(vtk_files):
69     mesh = pv.read(folder_path+'step'+str(i*outsteps)+'.vtk')
70     slip_velocity = mesh['Slipv[m/s]']
71     # Apply logarithmic transformation (e.g., base 10)
72     # Add small constant (e.g., 1e-10) to avoid log(0) issues
73     log_slip_velocity = np.log10(slip_velocity)
74
75     # Assign the transformed scalars back to the mesh
76     mesh['Log_Slipv[m/s]'] = log_slip_velocity
77     plotter.clear() # Clear previous mesh
78     plotter.add_mesh(
79         mesh,
80         scalars='Log_Slipv[m/s]',
81         cmap="plasma",
82         show_edges=False,
83         clim=scalar_range,
84         scalar_bar_args=scalar_bar_args
85     )
86
87     timeyear=state[i*outsteps,-1]/365
88     plotter.add_text(f"Time: {timeyear:.8f} yr", position="upper_left", font_size=14,
89                     color="white", shadow=True)
90     plotter.camera_position = 'xz'
91     plotter.write_frame() # Write frame to GIF
92
93 plotter.close()
94 print('Video has been saved.')

```

Listing 6: Visualize Results

output:

GPU acceleration Install cupy if you want to use GPU acceleration, we recommended to use conda in prompt terminal (e.g. CUDA 11.8):conda install -c conda-forge cupy cudatoolkit=11.8

Notes: CuPy relies on NVIDIA CUDA for GPU computing, so the following components are required:

1. **NVIDIA GPU Driver:** Ensure your system has a CUDA-capable NVIDIA GPU (check compatibility at <https://developer.nvidia.com/cuda-gpus>). The driver version must support the CUDA Toolkit version used by CuPy (e.g., CUDA 10.2–12.x for CuPy v13.x).
2. **CUDA Toolkit:** CuPy supports specific CUDA versions (check the latest compatibility at <https://docs.cupy.dev/en/latest/>). Common versions: CUDA 11.8 or 12.2 are widely used.

The GPU operates in a similar way to the CPU, only the output is converted to numpy each time. Reading model and parameters is the same as CPU. **Note:** Make sure to set GPU:True in the parameter.txt

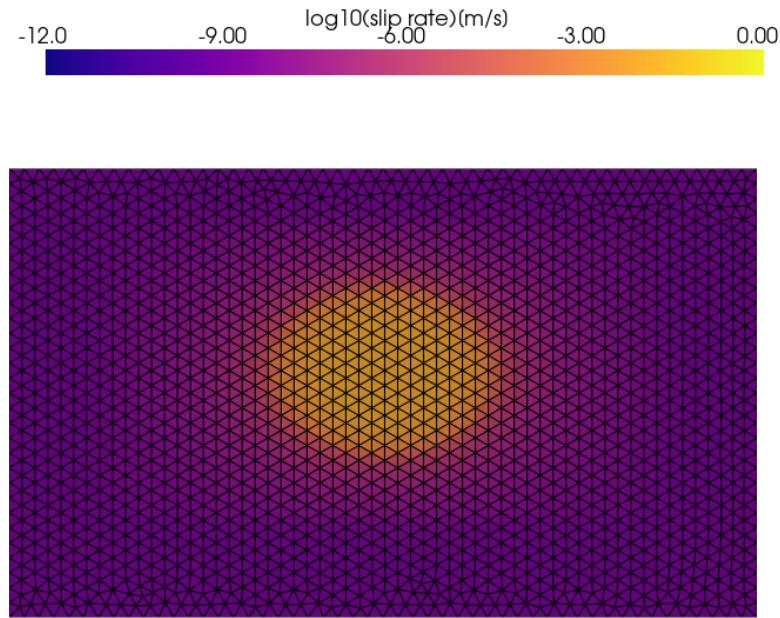


Figure 4: Snapshot of slip rate

```

2 | start_time=time.time()
3 |
4 | totaloutputsteps=int(sim0.Para0['totaloutputsteps'])
5 | directory='outvtk'
6 | if not os.path.exists(directory):
7 |     os.mkdir(directory)
8 |
9 | f=open('state.txt','w')
10| f.write('iteration time_step(s) maximum_slip1_rate(m/s) maximum_slip2_rate(m/s) time(s)\n')
11|     time(h)\n')
12|
13| if(sim0.useGPU==True): #GPU case
14|     sim0.initGPUvariable()
15|
16|     for i in range(totaloutputsteps):
17|         print('iteration:',i)
18|         if(i==0):
19|             dttry=sim0.htry
20|         else:
21|             dttry=dtnext
22|         dttry,dtnext=sim0.simu_forwardGPU(dttry)
23|
24|         #transform form cupy to numpy data
25|         sim0.slipv1=sim0.slipv1_gpu.get()
26|         sim0.slipv2=sim0.slipv2_gpu.get()
27|         sim0.slipv=sim0.slipv_gpu.get()
28|         sim0.slip=sim0.slip_gpu.get()
29|         sim0.Tt1o=sim0.Tt1o_gpu.get()
30|         sim0.Tt2o=sim0.Tt2o_gpu.get()

```

```

31     sim0.Tt=sim0.Tt_gpu.get()
32     #sim0.state1=sim0.state1_gpu.get()
33     #sim0.state2=sim0.state2_gpu.get()
34     sim0.rake=sim0.rake_gpu.get()
35     year=sim0.time/3600/24/365
36     if(i%10==0):
37         print('dt:',dttry,' Seconds:',sim0.time,' Days:',sim0.time/3600/24,'year',
38             year)
38         print(' max_vell:',np.max(np.abs(sim0.slipv1)), ' max_vel2:',np.max(np.abs(
39             sim0.slipv2)), ' min_Tt1:',np.min(sim0.Tt1o), ' min_Tt2:',np.min(sim0.Tt2o
40             ))
40     f.write('%d %f %.16e %.16e %f %f\n' %(i,dttry,np.max(np.abs(sim0.slipv1)),np.max
41     (np.abs(sim0.slipv2)),sim0.time,sim0.time/3600.0/24.0))
42
43     memory_info = process.memory_info()
44     print(f"Memory usage: {memory_info.rss / (1024 ** 2)} MB")
45
46     if(sim0.Para0['outputvtk']=='True'):
47         outsteps=int(sim0.Para0['outsteps'])#output steps
48         if(i%outsteps==0):
49             fname=directory+ '/step'+str(i)+'.vtk'
50             sim0.ouputVTK(fname)

```

Listing 7: conde to run GPU case

5.5.2 MPI-Based Execution on Linux

Step 1: Set Up Conda environment

1. Download latest Miniconda3, type: `wget https://repo.anaconda.com/miniconda/Miniconda3-latest-Linux-x86_64.sh -O miniconda.sh`
2. Install Miniconda with the following command: `bash miniconda.sh -b -u -p ~/miniconda3`

Parameters:

`-b`: Batch mode, automatically accepts the license agreement. `-u`: Updates the installation if the directory already exists. `-p ~/miniconda3`: Specifies the installation directory (here, miniconda3 in the home directory).

3. After installation, initialize Conda for terminal use: `~/miniconda3/bin/conda init`
4. Close and reopen the terminal, or run: `source ~/bashrc`
5. Verify the Installation,Check the Conda version: `conda --version`
6. After installation, create a new environment: `conda create -n PyQuake3D python=3.12`
7. Activate the environment: `conda activate PyQuake3D`

Notes: Dependencies: Ensure wget is installed. If not, install it:

`sudo apt install wget # For Ubuntu/Debian`

`sudo yum install wget # For CentOS/RHEL`

Step 2: Install Python and C++ Dependencies

1. Download from <https://github.com/Computational-Geophysics/PyQuake3D>
2. Install an MPI implementation and g++ compiler(including gcc and other related tools). Common options are:

- sudo apt update
 - sudo apt install g++
 - sudo apt install openmpi-bin libopenmpi-dev
1. Install PyQuake3D using pip: pip install -r requirements (make sure PyQuake3D environment is activated).
 2. Navigate to the src directory, run **make** to build TDstressFS_C.so. The generated library is called by the Python script Hmatrix.py via dynamic loading (e.g., using ctypes).

Notes1: MPI-CPU version is recommended for use on Linux because it requires compiling a C dynamic library, which is used for green's function calculation acceleration. Compiling C dynamic libraries (DLLs) on Windows can be less convenient compared to Linux or other Unix-like systems for several reasons, stemming from differences in tooling, ecosystem, and system design.

Notes2: PyQuake3D supports Python 3.8 and above, so there is no need to specify a specific version when installing the library.

Step 3: Examples for MPI-based backend

```

1 import readmsh
2 import numpy as np
3 import sys
4 import matplotlib.pyplot as plt
5 import QDsim
6 from math import *
7 import time
8 import argparse
9 import os
10 import psutil
11 from datetime import datetime
12 from mpi4py import MPI
13 import config
14
15
16
17
18 file_name = sys.argv[0]
19 print(file_name)
20
21 from config import comm, rank, size
22
23 import sys
24 #old_stdout = sys.stdout
25 #log_file = open("message.log", "w")
26 #sys.stdout = log_file
27
28 if __name__ == "__main__":
29     #eleVec, xg=None, None
30     #nodelst, xg=None, None
31     sim0=None
32     fnamePara=None
33     # jud_coredir=None
34     blocks_to_process=[] #Save block submatirx from Hmatrix
35     if(rank==0):
36         print('#
37             ')
38         print('# PyQuake3D: Boundary Element Method to simulate sequences of earthquakes
39             and aseismic slips')
40         print('# * 3D non-planar quasi-dynamic earthquake cycle simulations')
41         print('# * Support for Hierarchical matrix compressed storage and calculation')
42         print(f'# * Parallelized with MPI ({size} cpus)')
43         print('# * Support for rate-and-state aging friction laws')
44         print('# * Supports output to VTU formats')
45         print('# '
46             ')

```

```

44     try:
45         #start_time = time.time()
46         parser = argparse.ArgumentParser(description="Process some files and enter
47             interactive mode.")
48         parser.add_argument('-g', '--inputgeo', required=True, help='Input msh
49             geometry file to execute')
50         parser.add_argument('-p', '--inputpara', required=True, help='Input
51             parameter file to process')
52
53         args = parser.parse_args()
54
55     except:
56         # fnamegeo='examples/EAFZ-model/turkey.msh'
57         # fnamePara='examples/EAFZ-model/parameter.txt'
58         fnamegeo='examples/BP5-QD/bp5t.msh'
59         fnamePara='examples/BP5-QD/parameter.txt',
60         # fnamegeo='examples/cascadia/50km_43dense_35w.msh'
61         # fnamePara='examples/cascadia/parameter.txt'
62
63
64         print('Input msh geometry file:',fnamegeo, flush=True)
65         print('Input parameter file:',fnamePara, flush=True)
66
67         nodelst,elelst=readmsh.read_mshV2(fnamegeo)
68         Para=config.readPara(fnamePara)
69         sim0=QDsime.QDsime(elelst,nodelst,Para)
70         # output intial results
71         fname='Init.vtu'
72         sim0.writeVTU(fname,init=True)
73         #print(sim0.P)
74
75         sim0 = comm.bcast(sim0, root=0)
76         sim0.calc_greensfunc_mpi()
77         sim0.start()

```

Listing 8: Examples for MPI-based backend

Step 4: The visualization of the MPI-based backend is consistent with that of a single CPU/GPU

6 Code Structure and File Description

The PyQuake3D source code is organized to reflect its modular architecture and hybrid parallel computing design (Figure 5). 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.

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.
- `QDsime.py` and `QDsime_gpu.py` : Defines the `QDsime` class, which encapsulates the governing equations, numerical integrator, and interface to the selected Green’s function backend (dense in `QDsime_gpu.py` or hierarchical in `QDsime.py`).
 - `QDsime.Init_condition()`: Setting initial condition of fault model.

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

- `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.

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* *Table* and *Table 6*. Otherwise, you need to appropriately set the parameters of stress and frictional initial condition shown in *Table 4* and *Table 5*. ?? must be set up if fluid induced dilatancy and compaction is considered.

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

The total number of rows in the `InputHetoparameter` 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 column 9 and 10 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. Column 11 is the initial pore pressure, which is optional.

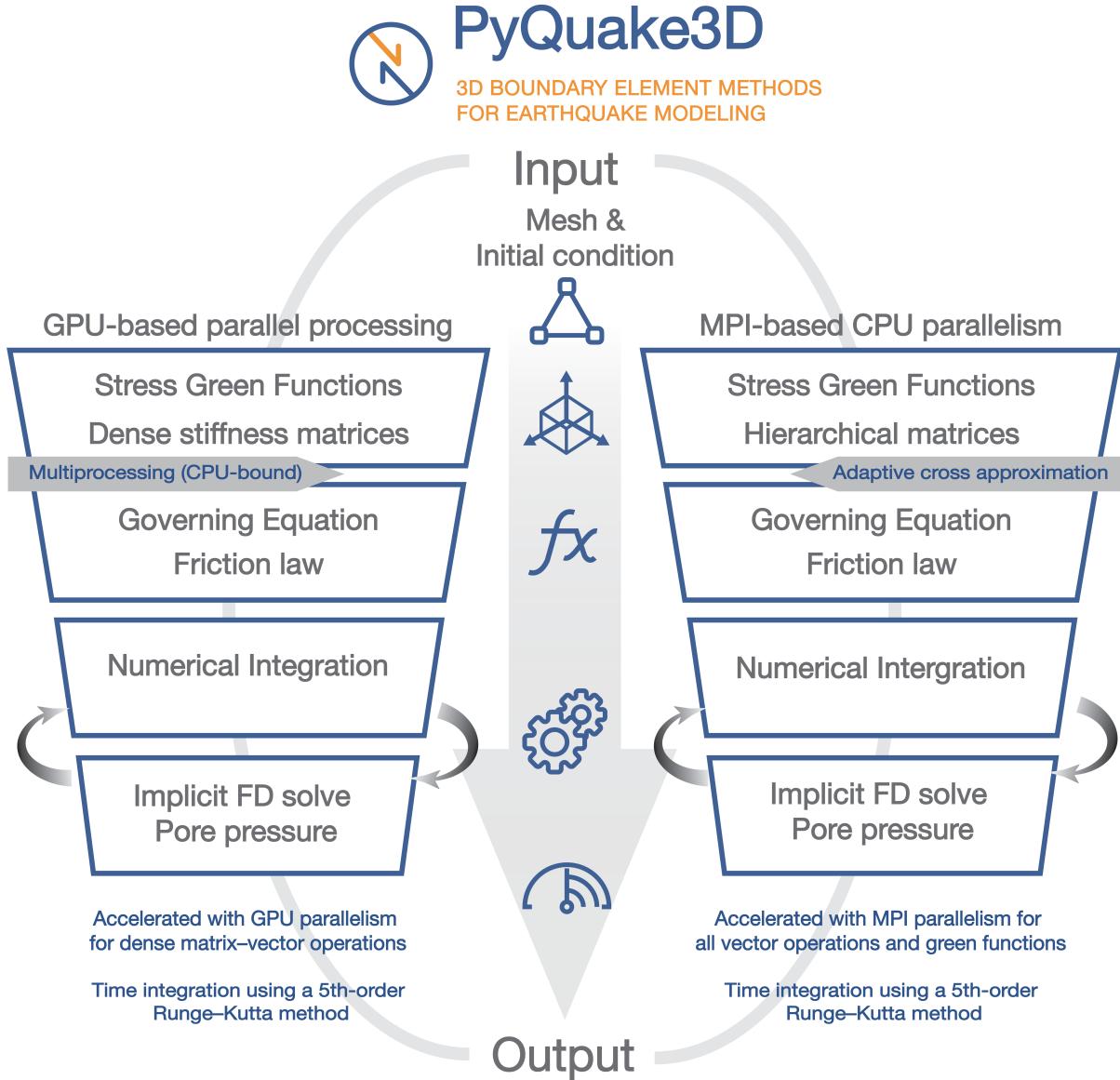


Figure 5: Overview of the PyQuake3D computational framework. The workflow includes input setup, solver implementation on GPU or CPU architectures, and output diagnostics. The GPU version uses dense matrix–vector operations accelerated with CUDA, while the CPU version applies hierarchical matrix compression and MPI-based parallelism.

8 Frictional heterogeneous model examples

Let's consider the heterogeneous frictional model (HF) to compute the earthquake cycle of strike-slip fault using MPI-based PyQuake3D (Figure 6). Listing 9 shows the entire input file required to describe the simulation. Note how the code is called, with the command

```
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 10. The screen output consists of three main parts:

Table 2: General Parameters

Parameter	Default	Description
Corefunc directory		The storage path for the kernel function matrix composed of stress Green's functions
Node_order	False	If ‘True‘, the node order of the triangular element is clockwise
save Corefunc	False	If ‘True‘, save corefuns Save the kernel function so that it does not need to be recalculated for the next time
Scale_km	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.
Hmatrix_mpi_plot	False (Only available for MPI verison)	If ‘True‘, draw the Hmatrix structure diagram, with different colors representing the sub-matrices calculated by different processes.
Using C++ green function	True (Only available for MPI verison)	If ‘True‘. Using C++ to calculate Green functions, else using python. Only available for MPI verison.
GPU	False (Only available for CPU/GPU verison.)	If ‘True‘, Using GPU parallel acceleration (cupy)
Max thread workers	50 (Only available for CPU/GPU verison.)	The number of processors in ProcessPoolExecutor to parallelize Green’s function calculations.
Batch_size	1000 (Only available for CPU/GPU verison.)	The number of batches in ProcessPoolExecutor to parallelize Green’s function calculations.
Input Hetoparamter	False	If ‘True‘, the heterogeneous stress and friction parameters are imported from external files.
Inputparamter file		The file name of imported heterogeneous stress and friction parameters
Lame constants	0.32×10^{11} Pa	The first Lame constant
Shear modulus	0.32×10^{11} Pa	Shear modulus
Rock density	2670 kg/m ³	Rock mass density
Reference slip rate	1×10^{-6}	Reference slip rate
Reference friction coefficient	0.6	Reference friction coefficient
Plate loading rate	1×10^{-9}	Plate loading rate

- Basic Information:** This section provides a summary of the key model settings, allowing users to verify the correctness of the configuration.
- 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

Table 3: Fluid Parameters

Parameter	Default	Description
If Dilatancy	False	If ‘True’, Coupled solve the fluid diffusion equation and quasi-dynamic model
Dilatancy coefficient	3×10^{-4}	Quantifies the volume change (dilation or contraction) in a porous medium due to shear deformation
Hydraulic diffusivity	$1 \times 10^{-5} \text{ m}^2/\text{s}$	The rate at which pore fluid diffuses cross the fault
Actively shearing zone thickness	$3 \times 10^{-3} \text{ m}$	The thickness of the actively shearing zone represents the width of the region undergoing significant shear deformation
Effective compressibility	$8 \times 10^{-11} \text{ Pa}^{-1}$	The volumetric strain response of the porous medium to changes in pore pressure
Constant background porepressure	2 MPa	Constant porepressure
Initial porepressure	2 MPa	Initial porepressure

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 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 7). 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 6b). PyQuake3D successfully captures a broad range of fault behaviors, including the progressive buildup and abrupt release of shear stress (Figure 7h); aseismic creep and afterslip; episodic slow-slip events without seismic 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 4: Stress and Friction 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

```

1 #Files and cells
2 Corefunc directory: core_HF
3 save Corefunc: True
4 Node_order: False
5 Scale_km: True
6
7 #Only available for mpi version
8 Hmatrix_mpi_plot:False
9 Using C++ green function:True
10
11 #Only available for single GPU/CPU version
12 Max_thread_workers: 50
13 Batch_size: 1000
14 GPU:False
15
16
17 #Property

```

Table 5: 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

```

18 | Lame constants: 32038120320.0
19 | Shear modulus: 32038120320.0
20 | Rock density: 2670
21 | InputHetoparamter: True
22 | Inputparamter file: initcondion.txt
23 |
24 | #Fluid
25 | If Dilatancy: False

```

Table 6: Output Setting

Parameter	Default	Description
totaloutputsteps	2000	The number of calculating time steps.
outsteps	50	The time step interval for outputting the VTU files.
outputSLIPV	False	If True, output slip rate for each step.
outputstu	True	If True, the VTU files will be saved in outvtk directory.

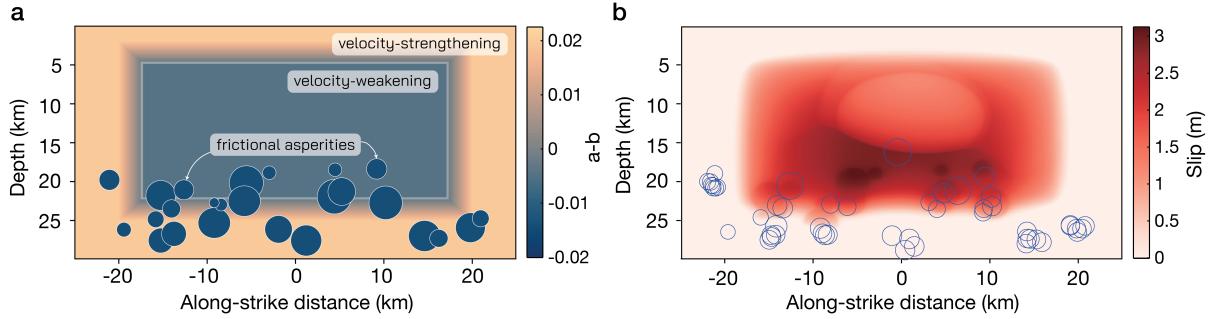


Figure 6: Frictional heterogeneity and rupture behavior in the fault model. (a) Initial distribution of the friction parameter $a-b$, with a central velocity-weakening region bounded by a velocity-strengthening margin. Dark blue circles mark strongly velocity-weakening patches representing small-scale 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.

```

26 Dilatancy coefficient: 3e-4
27 Hydraulic diffusivity: 1e-5
28 Actively shearing zone thickness: 3e-3
29 Effective compressibility: 8e-11
30 Constant porepressure: 2
31 Initial porepressure: 2
32
33 #Stress
34 Half space: True
35 Fix_Tn:True
36 Vertical principal stress: 1.0
37 Maximum horizontal principal stress: 1.6
38 Minimum horizontal principal stress: 0.6
39 Angle between ssh1 and X-axis: 90
40 Vertical principal stress value: 50
41 Vertical principal stress value varies with depth: True
42 Turnning depth: 5000
43 Normal traction solved from stress tensor: False
44 Shear traction solved from stress tensor: False
45 Rake solved from stress tensor: False
46 Fix_rake: 0
47 Widths of VS region: 5000
48 Widths of surface VS region: 2000
49 Transition region from VS to VW region: 3000
50
51
52 #Friction
53 Reference slip rate: 1e-6
54 Reference friction coefficient: 0.6
55 Rate-and-state parameters a in VS region: 0.0185
56 Rate-and-state parameters b in VS region: 0.001
57 Characteristic slip distance in VS region: 0.015
58 Rate-and-state parameters a in VW region: 0.0185
59 Rate-and-state parameters b in VW region: 0.024
60 Characteristic slip distance in VW region: 0.015
61 Rate-and-state parameters a in nucleation region: 0.01
62 Rate-and-state parameters b in nucleation region: 0.0185

```

```

63 Characteristic slip distance in nucleation region: 0.004
64 Initial slip rate in nucleation region: 3e-2
65 Plate loading rate: 1e-9
66 ChangefriA:False
67 Initlab: False
68
69 #nucleartion
70 Set_nucleation: False
71 Nuclea_posx: 34000
72 Nuclea_posy: 15000
73 Nuclea_posz: -15000
74 Radius of nucleation: 8000
75
76 #output
77 outputSLIPV: False
78 outputTt: False
79 totaloutputsteps: 1000
80 outsteps: 200
81 outputvtk: True
82 outputmatrix: False

```

Listing 9: Input of Heterogeneous frictional model

```

1 # -----
2 # PyQuake3D: Boundary Element Method to simulate sequences of earthquakes and aseismic
3 # slips
4 # * 3D non-planar quasi-dynamic earthquake cycle simulations
5 # * Support for Hierarchical matrix storage and calculation
6 # * Parallelized with MPI (12 cpus)
7 # * Support for rate-and-state aging friction laws
8 # * Supports output to VTK formats
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: 9.999999715603074e-10 Seconds: 9.973770190238952

```

```

49     Days: 0.00011543715497961749 year 3.162661780263493e-07
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 10: 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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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: Nikkhoo, M., & Walter, T. R. (2015). Triangular dislocation: an analytical, artefact-free solution. *Geophysical Journal International*, 201(2), 1119–1141.

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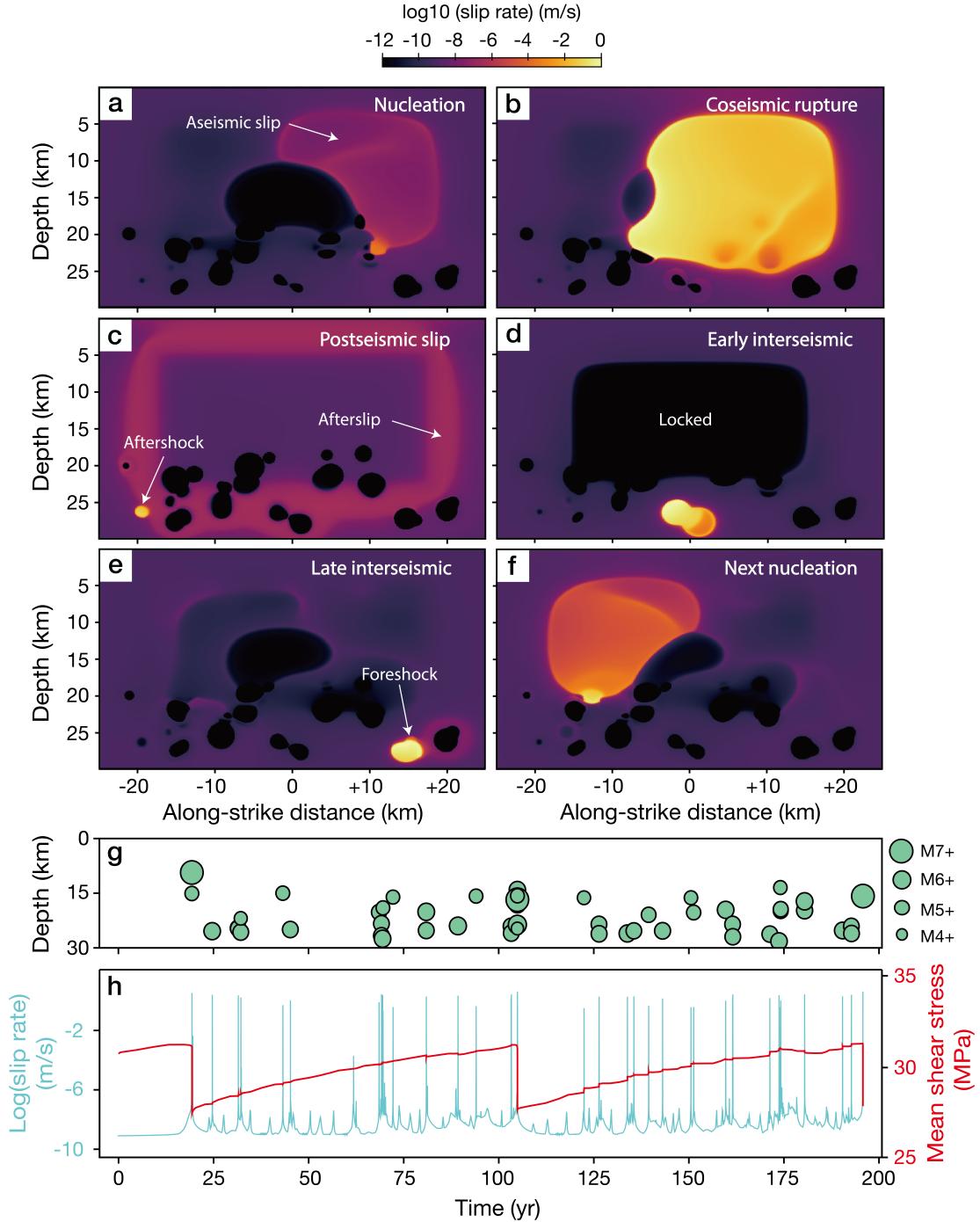


Figure 7: Spatiotemporal variations in slip rate and seismicity in the frictionally heterogeneous model. Panels (a-f) show slip rate evolution during key phases of the seismic cycle. (g) Spatiotemporal variations in event locations and magnitudes. (h) Time evolution of maximum slip rate and average shear stress.

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