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Title of your project

In partial fulfillment of MSc in High-performance Computing
in the School of Mathematics

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Abstract

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Keywords: keyword1, keyword2, keyword3,...

Contents

2 Introduction

Numerical methods of solving partial differential equations (PDE) have demonstrate far better performance than many other methods such as finite difference methods (FDM) [?], finite element methods (FEM) [?], Lattice Boltzmann Method (LBM) [?] and Monte Carlo Method (MC) [?]. In recent years, researchers in the field of deep learning have mainly focused on how to develop more powerful system architectures and learning methods such as convolution neural networks (CNNs) [?], Transformers [?] and Perceivers [?] . In addition, more researchers have tried to develop more powerful models specifically for numerical simulations. Despite of the relentless progress, modeling and predicting the evolution of nonlinear multiscale systems which has inhomogeneous cascades-scales by using classical analytical or computational tools inevitably encounts severe challanges and comes with prohibitive cost and multiple sources of uncertainty.

This project focuses on the promotions on performance gained from the parallel compute systems, in general, the FDMs and Neural Networks (NNs) are evaluated. Moreover, it prompted series Message Passing and Shared Memory hybrid parallel strategies using Message Passing Interface (MPI) [?] and Open Multi-processing (OpenMP) [?].

3 Related Work

To gain well quality solution of various types of PDEs is prohibitive and notoriously challanging. The number of methods avaliable to determine canonical PDEs is limited as well, includes separation of variables, superposition, product solution methods, Fourier transforms, Laplace transforms and perturbation methods, among a few others. Even though there methods are exclusively well-performed on constrained conditions, such as regular shaped geometry domain, constant coefficients, well-symmetric conditions and many others. These limits strongly constrained the range of applicability of numerical techniques for solving PDEs, rendering them nearly irrelevant for solving problems pratically.

General, the methods of determining numerical solutions of PDEs can be broadly classified into two types: deterministic and stochastic. The mostly widely used stochastic method for solving PDEs is Monte Carlo Method [?] which is a popular method in solving PDEs in higher dimension space with notable complexity.

3.1 Finite Difference Method

The Finithe Difference Method(FDM) is based on the numerical approximation method in calculus of finite differences. The motivation is quiet straightforward which is approximating solutions by finding values satisfied PDEs on a set of presctibed interconnected points within the domain of it. Those points are which referd as nodes, and the set of nodes are so called as a grid of mesh. A notable way to approximate derivatives are using Taylor Series expansions. Taking 2 dimension Possion Equation as instance, assuming the investigated value as, φ,

$$\frac{\partial^2 \varphi}{\partial x^2} + \frac{\partial^2 \varphi}{\partial y^2} = f(x, y) \tag{3.1.1}$$

The total amount of nodes is denoted with $N = 15$, which gives the numerical equation which governing equation 3.1.1 shown in equation 3.1.2 and nodes layout as shown in the figure 1

$$\frac{\partial^2 \varphi_i}{\partial x_i^2} + \frac{\partial^2 \varphi_i}{\partial y_i^2} = f(x_i, y_i) = f_i, \quad i = 1, 2, \ldots, 15 \tag{3.1.2}$$

In this case, we only need to find the value of internal nodes which i is ranging from 1 to 10. Next is aimming to solve this linder system 3.1.2.

3.2 Physics Informed Neural Networks

With the explosive growth of avaliable data and computing resouces, recent advances in machine learning and data analytics have yieled good results across science discipline, including Convolutional Neural Networks (CNNs) [?] for image recoginition, Generative Pre-trained Transformer (GPT) [?] for natual language processing and Physics Informed Neural Networks (PINNs) [?] for handling science problems with high complexity. PINNs is a type of machine learning model

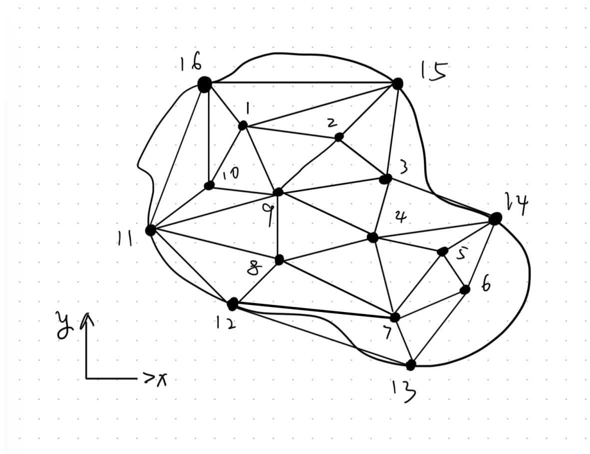

Figure 1: The Schematic Representa of of a 2D Computiational Domain and Grid. The nodes are used for the FDM by solid circles. Nodes $11-15$ denote boundary nodes, while nodes $1-10$ denote internal nodes.

makes full use of the benefits from Auto-differentiation (AD) [?] which led to the emergence of a subject called Matrix Calculus [?]. Considering the parametrized and nonlinear PDEs of the general form [E.q. 3.2.1] of function $u(t,x)$

$$u_t + \mathcal{N}[u;\lambda] = 0 \tag{3.2.1}$$

The $\mathcal{N}[\cdot;\lambda]$ is a nonlinear operator which parametrized by λ. This setup includes common PDEs problems like heat equation, and black-stokz equation and others. In this case, we setup a neural network $NN[t,x;\theta]$ which has trainable weights θ and takes t and x as inputs, outputs with the predicting value $\hat{u}(t,x)$. In the training process, the next step is calculating the necessary derivatives of u with the respect to t and x. The value of loss function is a combination of the metrics of how well does these predictions fit the given conditions and fit the natural law [Fig. 2].

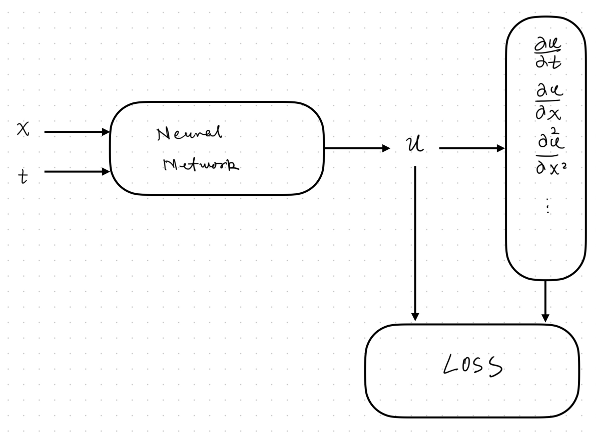

Figure 2: The Schematic Representa of a structure of PINN.

3.3 Finite Difference Time Domain Method

As described previously in the section 3.1, FDM could solve the PDEs in its original form where Finite Element and Finite Volume Methods gained results by solving modified form such as an integral form of the governing equation. Though the latter methods are commonly get better results or less computational hungery, the FDM has many descendants, for instance the Finite Difference Time Domain Method (FDTD) where it still finds prolific usage are computational heat equation and computational electromagnetics (Maxwell's equations [?]). Assuming the operator $\mathcal{N}[\cdot;\lambda]$ is set to ∇ where it makes E.q. 3.2.1 become to heat equation 3.3.1.

$$\frac{\partial u}{\partial t} - \lambda\left(\frac{\partial^2 u}{\partial x^2} + \frac{\partial^2 u}{\partial y^2}\right) = 0 \tag{3.3.1}$$

Using the key idea of FDM, assuming the step size in spatio-time space are Δx, Δy and Δt, we could have a series equations which have form [E.q. 3.3.2].

$$\frac{u_{i,j}^{n+1} - u_{i,j}^{n}}{\Delta t} = \lambda\left(\frac{u_{i+1,j}^{n} - 2u_{i,j}^{n} + u_{i-1,j}^{n}}{\Delta x^2} + \frac{u_{i,j+1}^{n} - 2u_{i,j}^{n} + u_{i,j+1}^{n}}{\Delta y^2}\right) \tag{3.3.2}$$

when the time step size satisfies the Couran, Friedrichs, and Lewy condition (CFL[?]). We could get the strong results by iterating the equation 3.3.2, or more specifically using equation 3.3.3 to get the value u of next time stamp $n+1$ on nodes i, j.

$$u_{i,j}^{n+1} = u_{i,j}^{n} + \frac{\lambda\Delta t}{\Delta x^2}\left(u_{i+1,j}^{n} - 2u_{i,j}^{n} + u_{i-1,j}^{n}\right) + \frac{\lambda\Delta t}{\Delta y^2}\left(u_{i,j+1}^{n} - 2u_{i,j}^{n} + u_{i,j+1}^{n}\right) \tag{3.3.3}$$

also shown in the figure 3.

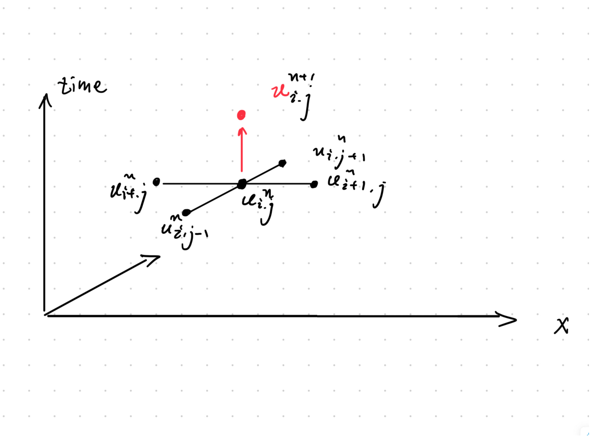

Figure 3: The Schematic Representa the computational spatio-time domain of FDTD methods.

4 Problem Setups

Due to the inherent limitations of current computing systems, obtaining sufficiently precise solutions is both computationally expensive and time-consuming. These challenges arise from the constraints imposed by the clock speed of computing units, as described by Moore's Law [?], as well as the relatively low communication speeds between these units. While modern numerical methods have advanced to a level where they can produce satisfactory results within acceptable time frames across many research domains, the increasing scale of problems we aim to solve has driven the search for more cost-effective approaches. This has led to a growing interest in neural networks as a promising alternative.

In this project, I aim to evaluate the performance of the Finite-Difference Time-Domain (FDTD) method and the Physics-Informed Neural Network (PINN) model within parallelized computing environments by find the steady-state solution of PDEs. These two methodologies broadly represent the current approaches to handling PDEs, specifically CPU-based parallelization and GPU-based parallelization.

4.1 General Form

Starting with the general form of the PDEs, rather than the specific euqations, is because different equations give perform differently on the same compute system. To this end, consider the previously discussed form of PDEs shown in equation 3.2.1 which parametrized by number λ and an operator $\mathcal{N}[\cdot;\lambda]$. Moreover, we assume the variable x is a 2D or 3D spatio vector which is written in $\vec{x} \in \mathbb{R}^d$, $d = 2, 3$.

$$\begin{aligned} &\frac{\partial u}{\partial t}(t,\vec{x}) + \mathcal{N}\left[u(t,\vec{x});\lambda\right] = 0, && \vec{x} \in \Omega, t \in [0,+\infty) \\ &u\,(0,\vec{x}) = \varphi(\vec{x}), && \vec{x} \in \Omega \\ &u\,(t,\vec{x}) = g(t,\vec{x}), && \vec{x} \in \overline{\Omega}, t \in [0,+\infty) \end{aligned} \tag{4.1.1}$$

The domain of this PDE system is considered between 0 and 1, where is denoted with $\Omega = [0,1]^d$, $d = 2, 3$. To these setups, we have the general form of the PDEs we are going to investigated, shown in equations 4.1.1 The boundary condition shown in E.q. 4.1.1 is Dirichlet Condition known as first type boundary condition, where as the second type boundary condition (Von Neumman) [E.q. 4.1.2] gives the other form of $u(t,\vec{x})$ at the boundary $\overline{\Omega}$.

$$\frac{\partial u}{\partial \vec{x}} = g(t,\vec{x}), \;\; \vec{x} \in \overline{\Omega}, \;\; t \in [0,+\infty) \tag{4.1.2}$$

4.2 Specific Form

With general form proposed in section 4.1[E.q. 4.1.1], I specify a particular form of this heat problem to help us to have better understand the quality of our solutions and programs. In

2 dimension space, the domain $\Omega = [0,1]^2 \in \mathbb{R}^2$ and its boundary denoted with $\overline{\Omega}$, the initial condition $\varphi(x,y) = 0$. such problem has the certain form below

$$
\begin{aligned}
&\frac{\partial u}{\partial t} = \alpha \left(\frac{\partial u^2}{\partial^2 x} + \frac{\partial u^2}{\partial^2 y} \right) && (x,y) \in \Omega,\ t \in [0,+\infty) \\
&u(0,x,y) = \varphi(x,y) = 0 && (x,y) \in \Omega \\
&u(t,x,y) = g(x,y) = \begin{cases} y, & x = 0, y \in (0,1) \\ 1, & x = 1, y \in (0,1) \\ x, & y = 0, x \in (0,1) \\ 1, & y = 1, x \in (0,1) \end{cases} && t \in [0,+\infty)
\end{aligned}
\tag{4.2.1}
$$

With given format, and $\alpha = 1$, we have the analytical solution of this equations, where is

$$
u(t,x,y) = x + y - xy,\ \ (x,y) \in \Omega,\ t \in [0,+\infty) \tag{4.2.2}
$$

In 3 dimension space, similarly, with identical initial condition set up to 0, coefficient $\alpha = 1$, the boundaries are

$$
u(t,x,y,z) = g(x,y,z) = \begin{cases} y + z - 2yz, & x = 0, \\ 1 - y - z + 2yz, & x = 1, \\ x + z - 2xz, & y = 0, \\ 1 - x - z + 2xz, & y = 1, \\ x + y - 2xy, & z = 0, \\ 1 - x - y + 2xy, & z = 1 \end{cases},\ t \in [0,+\infty) \tag{4.2.3}
$$

In such case, the analytical solution has for form below

$$
u(t,x,y,z) = x + y + z - 2xy - 2xz - 2yz + 4xyz,\ \ (x,y,z) \in \Omega,\ t \in [0,+\infty) \tag{4.2.4}
$$

4.3 Discretization

To begin with discretizing the objects or regions we intend to evaluate via matrices, we consider a straightforward approach: using the coordinates in $d = 2,3$ dimensional spaces and the function values at those points to simplify the objects. This naive approach works well for investigating objects with regular shapes, such as a cube.

For the FDTD (Finite-Difference Time-Domain) method, we use a finely generated d-cube with shape $\{n_i\}_i^d$. Including the boundary conditions, the cube has $\prod_i (n_i + 2)$ nodes. It requires $4\prod_i (n_i + 2)$ bytes for float32 or $8\prod_i (n_i + 2)$ bytes for float64 to store in memory. With this setup, for equally spaced nodes, we have:

$$
\Delta x_i = \frac{1}{n_i - 1} \tag{4.3.1}
$$

Unlike the previously generated regular grid of points with dimensions $n_x n_y n_z$, another strategy is to randomly generate the same number of points based on the same known conditions, covering both the central part and the boundary. In this scenario, shown in figure, there are $n_x n_y n_z$ central points, with function values set according to the boundary conditions, and $2 \times (n_x n_y + n_y n_z + n_z n_x)$ boundary points to be solved. This set of points can be used for training a PINN model.

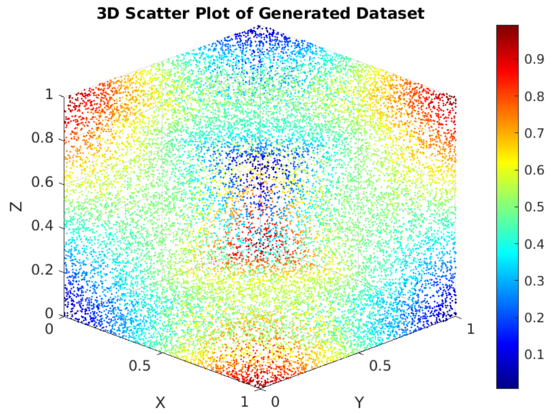

Figure 4: Randomly general dataset for 3D PINN model training.

4.4 Accuracy

When we tried to represent numbers using arithmetic in binary, decimal or hexadecimal, truncation always affects the precision of every number, or so called as round-off-error.

Round-off Error

In IEEE-754 [?] standards, a 32-bit floating pointer number, single precision, obligatorily represented with 23-bit mantissa, 8-bit exponent and 1-bit for sign. Where as 64-bit floating number, double precision, also ubiquitous used, which has 11-bit exponent and 52-bit mantissa. After almost three decades development, not only single and double precisions (float32, float64) are ubiquitously in use, also more formats such as fp4, fp8, and fp16 etc. Both of them follows the simple form of exponent k, sign n and mantissa N. [?]

$$2^{k+1-N} n$$

Round-off errors are a manifestation of the fact that on a digital computer, which is unavoidable in numerical computations. In such case, the precision of the number depends on how many bytes are used to store single number. For instance, a float32 number provides $2^{-23} \approx 1.2 \times 10^{-7}$, and a double precision number gives $2^{-53} \approx 2.2 \times 10^{-16}$, such number is called machine ϵ which is the smallest number the machine can represent with given format.

In numerical methods I investigated, the FDTDs are conventionally using double precision number so that the programs can treat extreamly large and small numbers simultaneously in the same computation, without worring about the round-off errors. However, as mentioned, fp32 and fp16 are also popular use in scientific computing, especially in machine learning training process. While the lasted training GPUs are integrated compute accelarate unit for low precision floating numbers. [?].

Floating-point Arithmetic

The other type loss comes from the arithmetic operations on two numbers x, y. The standard model holds that

$$fl(x \operatorname{op} y) = (x \operatorname{op} y)(1 + \delta), \quad |\delta| < \epsilon \tag{4.4.1}$$

where the op stands for the four elementary operations: $+, -, \times, /$. [?, ?, ?, ?].

4.5 Computiational Topology

The computational topology is critically important when we are programming parallel PDEs solver softwares. Put the strongly speed-dependent data into the slow memory could make entire program slower.

Callan The cluster we are using for this project is `Callan` [?] which has 2 CPUs per compute node, and each CPU has 32 cores with single thread. The Non-Uniform Memory Access (NUMA) nodes are layout as following Accessing the other NUMA node's memory reduces the

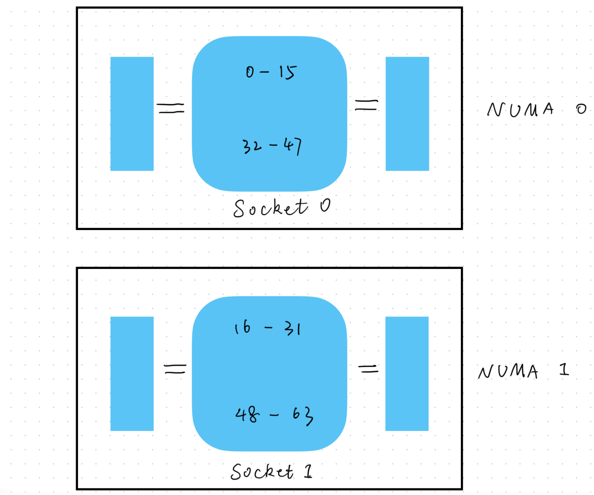

Figure 5: NUMA topology of single node on Callan

bandwidth and also the latency, though the bandwidth is commonly high enough, the latency can increase by 30% to 400% [?]. This latency becomes dangerous when writing shared memory parallel programs.

5 Methedology

5.1 General Setups

Initially, we need to determine the data types to be used and define macros for assertions and helper functions to ensure that the program can detect common bugs and report their locations. These features can also be disabled in the release version for performance optimization. Such details are defined in the `assert.hpp`, `helper.hpp`, and other related header files located in the subfolder.

5.2 Template Multi-dimension Matrix Detail Design

The FDTD method is a type of FDM. The main idea behind FDM is briefly outlined in Section 3.1. The challenge lies in implementing it in a computer system to ensure it runs both correctly and efficiently. Also, the data types I am using for storing sizes are unit32_t and unit64_t while I used them as Dworld and Qworld respectively, also are defined as size_type and super_size_type in __detail namespace.

Performance Balancing

Template Class Instead of doing this by using hierarchy in C++, which will cause the memory of object becomes complicated and unpredictable, and leading to scattered data members between base and derived class objects. This scattering can increase the cache misses which accessing these members, as the data might not be contiguous in memory. Also, with deep inheritance hierarchies, program has higher change to occur diamond problems, since it increases the code complexity. In detail, the diamond problem leads the duplicate inheritance and ambiguity in the method resolution, which will drop performance down again. Although, it is solvable by using `virtual` inheritance, but again, it increase the complexity.

In such case, I chose to use template class to design the matrix object, which implement compile-time polymorphism as opposed runtime polymorphism provided by inheritance and virtual functions. With such template design, the compiler makes the decisions about which function or class instantiate is made at compile time, eliminating the need for `vtables` and indirect function calls, which leads to more efficient code.

Memory Management Rather than using the standard library's (STL) vector module, which can be slower due to the overhead of row pointers, I opted to build the Matrix object using a unique pointer (`std::unique_ptr`), which includes only basic features such as reset, swap, and most importantly, a destructor that automatically deletes pointers. This approach enhances the safety of memory management in our programs. Additionally, from a safety perspective, given that I implemented many features within the matrix object, I followed standard library conventions for naming. This includes using the `__detail` namespace within namespace `multi_array` to hide objects and features that are not intended for direct use by the end user.

Template Object Design of Matrix Shape

Strides Besides that, in the multidimensional cases, the size in each dimension is not enough for accessing variables, this is where we need the `strides` member variable, which stores the number of element the operator needs to skip in each dimension. The `__multi_array_shape` object is encapsulated within the `__detail` namespace and serves as a member variable of the later template object for the multi-dimensional matrix. This object includes a member variable defined using the STL vector, as the shape object primarily stores the sizes for each dimension, which typically requires only a small amount of space. Additionally, this object provides member functions to access the size of a given dimension.

Algorithm 1 Stride implementation

```
dims                                   # STL vector, stores the matrix's size in each dimension.
strides                                # STL vector, has the same size with dims.
n = dims.size()                        # Store the dimension of matrix.
strides[d-1] = 1;                      # Stride is 1 in the first dimension.
for d = n - 1; d > 0; –d do
    strides[d-1] = strides[d] * dims[d]    # Determine stride in the latter dimension.
end for
return strides
```

Performace Balancing In certain scenarios, we only require the shape information of a matrix without needing to access the entire matrix object. Accessing the shape information through well-defined operators is a more efficient way to handle multidimensional matrices. This is particularly crucial in parallel programming, where understanding the shape of a matrix is of critical importance. Sometimes, a process may need to know the shape of matrices stored on other processes. In such cases, using this matrix object as a local variable within functions increases the likelihood that the compiler will store it in a register, which is generally faster than using heap or stack memory. In addition, it includes check and cast functions that allow the user to verify if the template data type `__T` is signed using `constexpr`. The `constexpr` keyword ensures that this check occurs at compile time, and if the data type is not legal, the program will assert and provide a message indicating that the indexing value must be a non-negative number.

Template of Multi-dimensional Matrix Implementation

The Matrix in this project is designed to support various data types in C++. Consequently, the matrix is implemented as a template class with several essential features, template variable `__T` and `__NumD`, for the value data type and number of dimension, also including iterators, swap functionality, fill operations, and support for the IO stream operator «. To facilitate this, the `__array_shape` object is used to explicitly manage and access the array's shape information.

Operator () The hard part of this object designed is the support template number of dimension, whereas the dimension is integer not less than 1, the operator of access element is designed by following algorithm

Algorithm 2 Operator `(Ext ... exts)` of template matrices object `__detail::__array`

```
__NumD, __T;                                    # Template variables: dimension, data type.
FINAL_PROJECT_ASSERT_MSE                        # Number of Arguments must Match the dimension.
index = 0, i = 1                                # Initialize variables in advance.
indices[] = __shape.check_and_cast(ext)         # The indexes number must none-negative number.
for i < __NumD; ++i do
  index += indices[i] * __shape.strides[i]
end for
FINAL_PROJECT_ASSERT_MSE                        # Boundary checking.
return __data[index]
```

Overload operator « In order to print the multi-dimension array with operator «, I designed a recursive helper function to print the matrix on given dimension. Thus we could call the function on the first dimension, and it will recursively print all dimensions.

5.3 Template Multi-dimension Matrix Interface Design

With contiguity of safety, this object of multi-dimension array is accessible to users without direct visit to the memory space where store values of matrix.

Resource Acquisition Is Initialization (RAII)

This private object has only a member variable, a unique pointer to the template `__array`, and other member function provide necessary features to operating on it. Smart pointers acquire resources in their constructor and automatically release them in their destructor, which is the essence of RAII. By releasing resources in the destructor, smart pointers help prevent resource leaks. When an exception occurs, smart pointers automatically release resources, preventing resource leaks, thus it enhanced the safety level of using resources, reduce the potential memory leak problems.

Algorithm 3 Recursive Function to Print Multi-Dimensional Array

```
current_dim, offset;                                   # Parameters: current dimension, offset.
Dims __Dims;                                           # Template variable: number of dimensions.
if current_dim == __Dims - 1 then
  os << "|"                                            # Start printing last dimension.
  for i from 0 to arr.__shape[current_dim] - 1 do
    os << std::fixed << std::setprecision(5) << std::setw(9) <<
    arr.__data[offset + i];                            # Print array elements with formatting.
  end for
  os << " |\n";                                        # End of current row in the last dimension.
else
  for i from 0 to arr.__shape[current_dim] - 1 do
    next_offset = offset;                              # Initialize next offset.
    for j from current_dim + 1 to __Dims - 1 do
      next_offset *= arr.__shape[j];                   # Update next offset based on shape.
    end for
    next_offset += i * arr.__shape[current_dim + 1];   # Finalize next offset for
    recursion.
    self(self, arr, current_dim + 1, next_offset);     # Recursive call to print next
    dimension.
  end for
  os << "\n";                                          # Print a newline after each dimension.
end if
```

Template Multi-dimension IO for writing to/reading from file

Initially, the multi-dimension matrix has variables shape, and values which given dimension and size in each dimension. This template design end up with these variable can be stored in given data types also leads with lower portability. To avoid such problems and from other point of views, I chose to store the matrices in binary format, rather than other type files. There are couple benefits of doing so,

1. Compatibility and Portability: The format of binary files is relatively stable and can be easily used in different programming environments or applications. Unlike `.txt` files, `.mat` files those has less compatibility across different platforms.

2. I/O Performance: Binary files can perform block-level I/O operations directly without needing to parse text formats or convert data types. This usually makes reading and writing binary files much faster than `.txt` files, especially when dealing with large-scale multidimensional matrix data.

3. Support MPI IO: Binary files support the MPI IO, which provides a significant reduction in the cost of communication, when storing and reading the large scale matrices.

However, the IO does not play a critical role in effects performance of FDTD algorithms, if and only if we need to store or load the data during evolving the arrays.

5.4 MPI Parallel Environment Design Scheme

MPI Setups

Environment Similar to how `malloc` in C and `new` in C++ require manual memory management, the MPI environment also necessitates explicit initialization and finalization. However, unlike the efficient implementation of smart pointers in the STL, Boost.MPI[?] -a high-level parallelism library— may not be the optimal choice for high-performance programs. Therefore, I chose to design a custom MPI environment that encapsulates the necessary features specific to this project.

The `mpi` namespace, a sub-namespace of `final_project`, provides the `environment` class. This class integrates MPI initialization using the constructor, which invokes `MPI_Init_thread`, provides multi-threading shared memory parallelism in MPI, and MPI finalization through the destructor, which calls `MPI_Finalize`.

It also offers direct access to the rank and the number of processors within the MPI communicator. Furthermore, I have explicitly deleted the copy and move assignment operators to enhance safety. This design decision aligns with the RAII principle, ensuring that MPI environment resources are automatically managed, thereby preventing leaking and using-uninitialized problems.

Types and Assertions Aligned meta-programming with polymorphism principles, I designed a template function to retrieve the corresponding MPI basic data types, leveraging the fundamental data types I defined as traits at the outset. Moreover, I provides some MPI macros in assert file, these macros provide a unified interface for dealing with MPI-related errors, ensuring that MPI errors are handling consistently, safely.

MPI Topology (`Cartesian`)

The namespace `topology` is a sub-namespace of `mpi`, the template Cartesian structure is the mainly used object in following problems. To optimize memory usage, this object maintains only essential multi-dimension matrices' global and local shape member variables. It also contains a MPI Communicator and MPI value data type, halo data type along with the neighbors' rank in the source and dest sites. To ensure the MPI security, the copy and move constructors as well as assignment operators are manually removed. Additionally, the destructor is customized for properly release halo data type and Cartesian communicator.

Determine the local matrix's localtion Evenly distributing tasks across processes is of critical importance. To address this, I designed an algorithm to divide an integer N evenly to n clients, where I could put it in use in many cases. Rather than implementing a standalone function, I chose to implement a lambda function, which is a feature in C++ that do not significantly impact the performance. It allows me to design a small function which is not frequently use or play a key role in performance. Ideally, this function will be only

Algorithm 4 Lambda Function (decomposition): Split tasks evenly to n processes evenly

```
n, rank                 # const Integers, total number and current rank of Processor.
N                       # constant Integer, Problem size.
s, e                    # Integer, start, end indexes.
n_loc = n / N           # Divide the problem evenly.
remain = n % N          # Get the remaining tasks.
s = rank * n_loc + 1    # Calculate the start indexes.
if rank < remain then
    s += rank           # Give a task to process the rank is smaller than remain.
    ++n_loc             # Update local number of tasks.
else
    s += remain         # Add the remain to start index, after split remains.
end if
e = s + n_loc + 1       # Get the ending indexes
if e > n or rank == N - 1 then
    e = n               # If it is the end of all.
end if
```

called when I construct the MPI topology based multi-dimension array, where I need cut the global matrix's shape evenly and create local matrices with local shape. Using local shape to create local matrices is obviously a memory-saving techniques when the problem size gets larger. Eventually, the lambda function is only applied in constructor of template Cartesian structure, which constructed from an input global and a MPI topology environment.

Moreover, the topology information is determined by `MPI_Cart_coords` for the coordinates and `MPI_Cart_shift` the neighbors of each process in all dimension. Below is a example [Fig. 6] of cartesian topology of 24 processors, with no period in all dimensions.

Determine MPI datatypes for communication In order to do MPI communications, the source and the destination of every process are necessary, also the datatype. When working with the meta-designed multidimensional matrix, we need to utilize the function `MPI_Type_Create_subarray` to create essential halo datatypes.

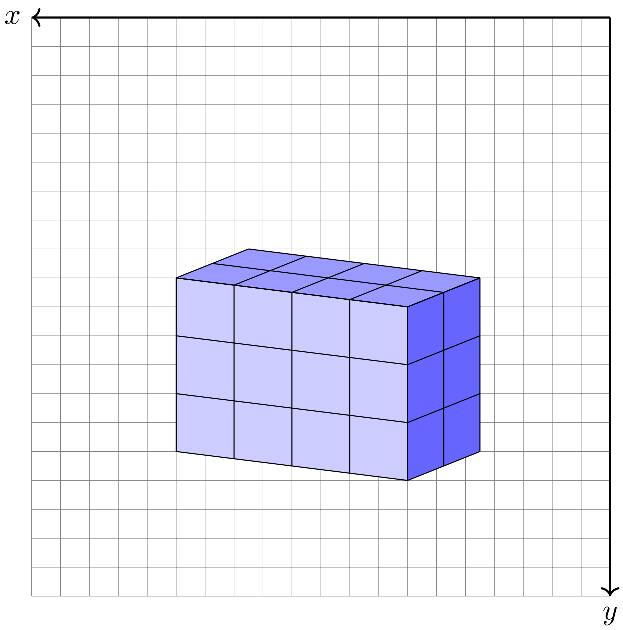

Figure 6: An example of MPI Cartesian topology Scheme of 24 processors.

```
array_size, array_subsize, array_starts={0}    #std::array<Integer, NumD>, the information of matrix.
for i = 0 : NumD do
    Split tasks in dimension i by calling decomposition
    array_size = local shape
    array_subsize = array_size - 2
end for
for i=0 : NumD do
    temp = array_subsize[i]                     # Store the number temporally.
    array_subsize[i] = 1
    MPI_Type_Create_subarray and MPI_Type_commit()    # Create halo in dimension i and commit.
    Restore temporal array sub-size.
end for
```

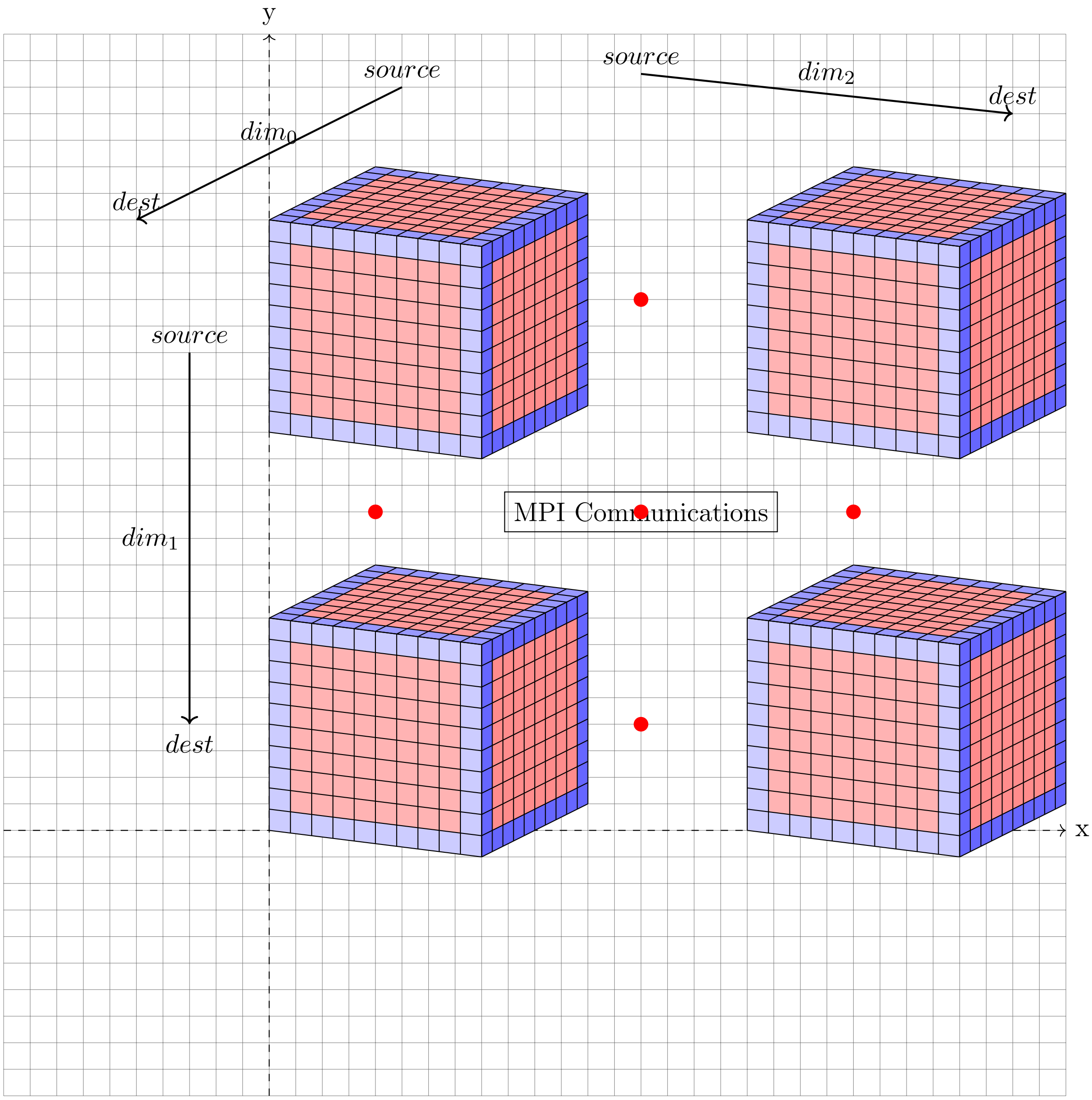

Figure 7: A 3D MPI Communication Scheme of 8 processors between 3 dimension matrices.

5.5 Template Distributed Multi-dimension Matrix Design

Detail Object Design

Adhering to the STL safety routines, I chose to create detail template class object, hidden from users, named `__array_Cart<class __T, __size_type __NumD>`. Here, the `__T` represents the value type, `__size_type` specifies the type of number of dimensions. Since it is internal and not exposed from users, I decided to directly use other detail objects as member variables rather than smart pointers. In this context, Cartesian matrix has public member variables `__array` and `topology::Cartesian`, and provides memory operations. But the copy, move constructors and assignment operators are removed. This approach enhances both performance both performance and simplicity by avoiding unnecessary abstractions in the internal design while maintain a robust memory management.

Distributed operator « The STL os stream operator « prints the matrices of all processes in sequence which build on multidimensional matrix's. Thus the Unix standard `fflush` function is utilized for flushing the cache in terminal, to ensure the stdout is print immediately.

User Interface Design

The `array_Cart<class T, size_type NumD>` is an object exposed to users, whereas only provides limited access to member variables by smart pointer. As the size of matrices stored, it becomes clear that memory management is critically important. Secondly, especially in MPI distributed matrices, exposing direct memory access by set it to public member is dangerous. With the profits mentioned in Section 5.3, using unique pointer brings more benefits in this scenario,

1. MPI program memory management has higher complexity level. Adhering RAII routines, the resources are bind with object, including MPI objects, and will be deleted as the object destructed.

2. Simplifying Concurrency Control. Synchronization between processes is a critical issue. By using the RAII, user could unsure the resources are locked or released automatically, preventing the risk of deadlocks and resource contention.

5.6 Template Function Gather of Cartesian Distributed Multi-dimension Matrix

5.7 Physics Informed Neural Networks

CUDA parallel

Hybrid Parallel

6 Implementation

6.1 Finite Difference Methods

Pure Message Passing Parallel

Hybrid Parallel

6.2 Physics Informed Neural Networks

CUDA parallel

Hybrid Parallel

6.3

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