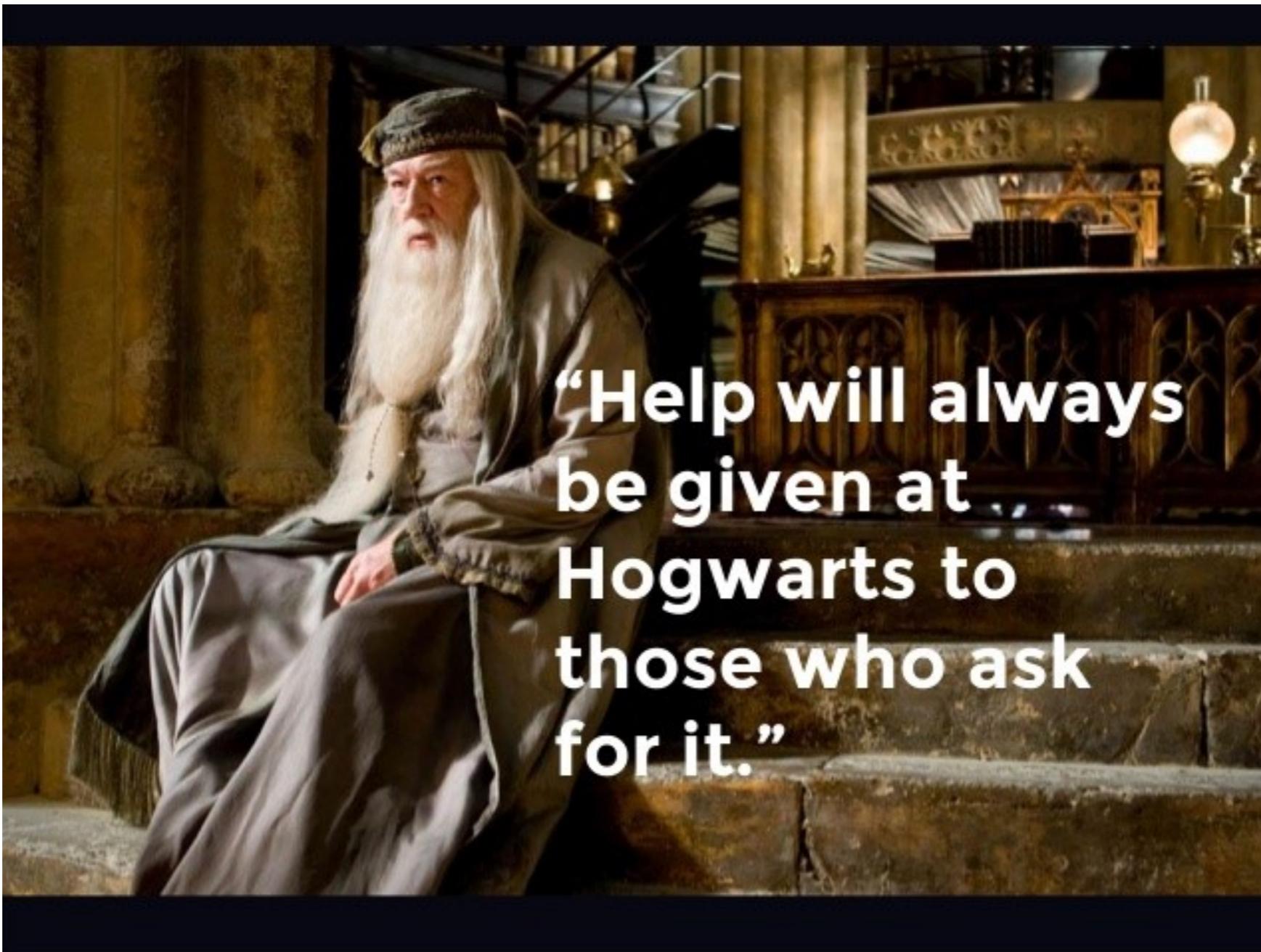


Numerical methods and integral equations

MATLAB: tips and tricks



'help <function name>', 'help <classname>', 'help <classname>/<function name>' provide useful information about how to use well-documented codes in MATLAB

MATLAB: tips and tricks

Don't write buggy codes!



But if you do, and when in doubt, just plot: Printing and plotting are the most efficient ways of debugging your code

MATLAB: tips and tricks

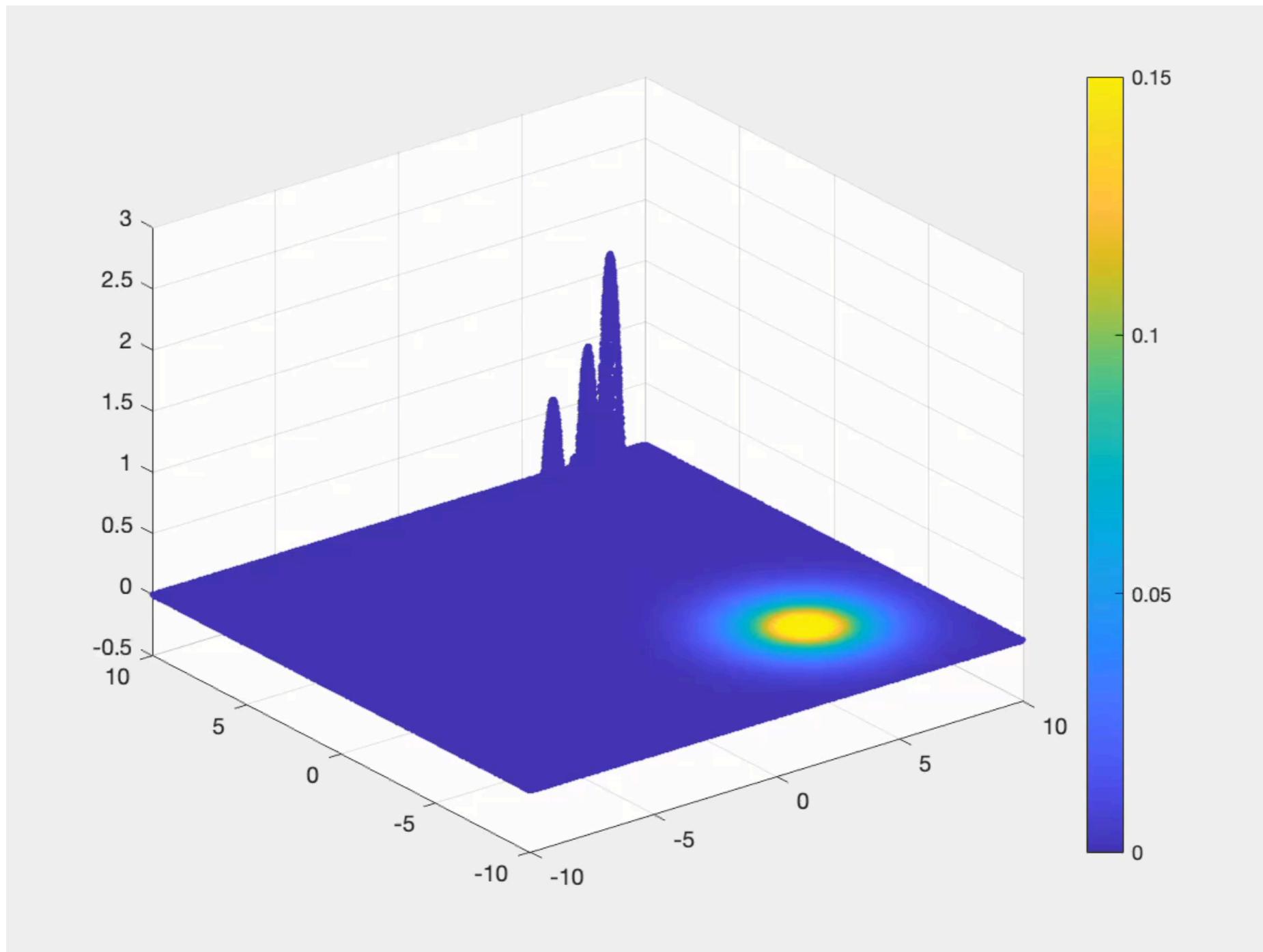
Dot doesn't dot, but not dot dots



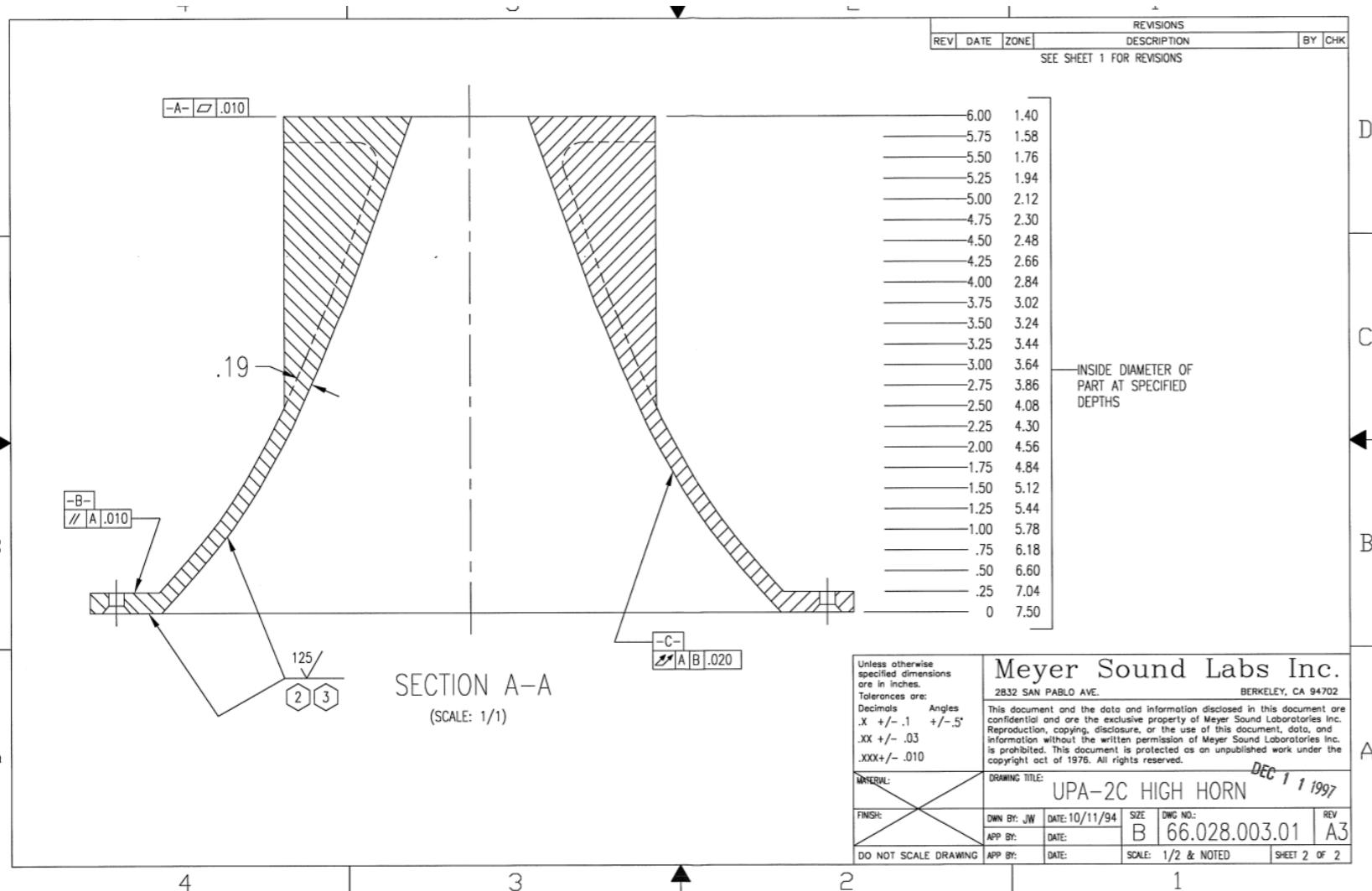
Be mucho careful with MATLAB's pointwise multiplication (.*) vs dot product ((*))

Applications: Kelvin waves

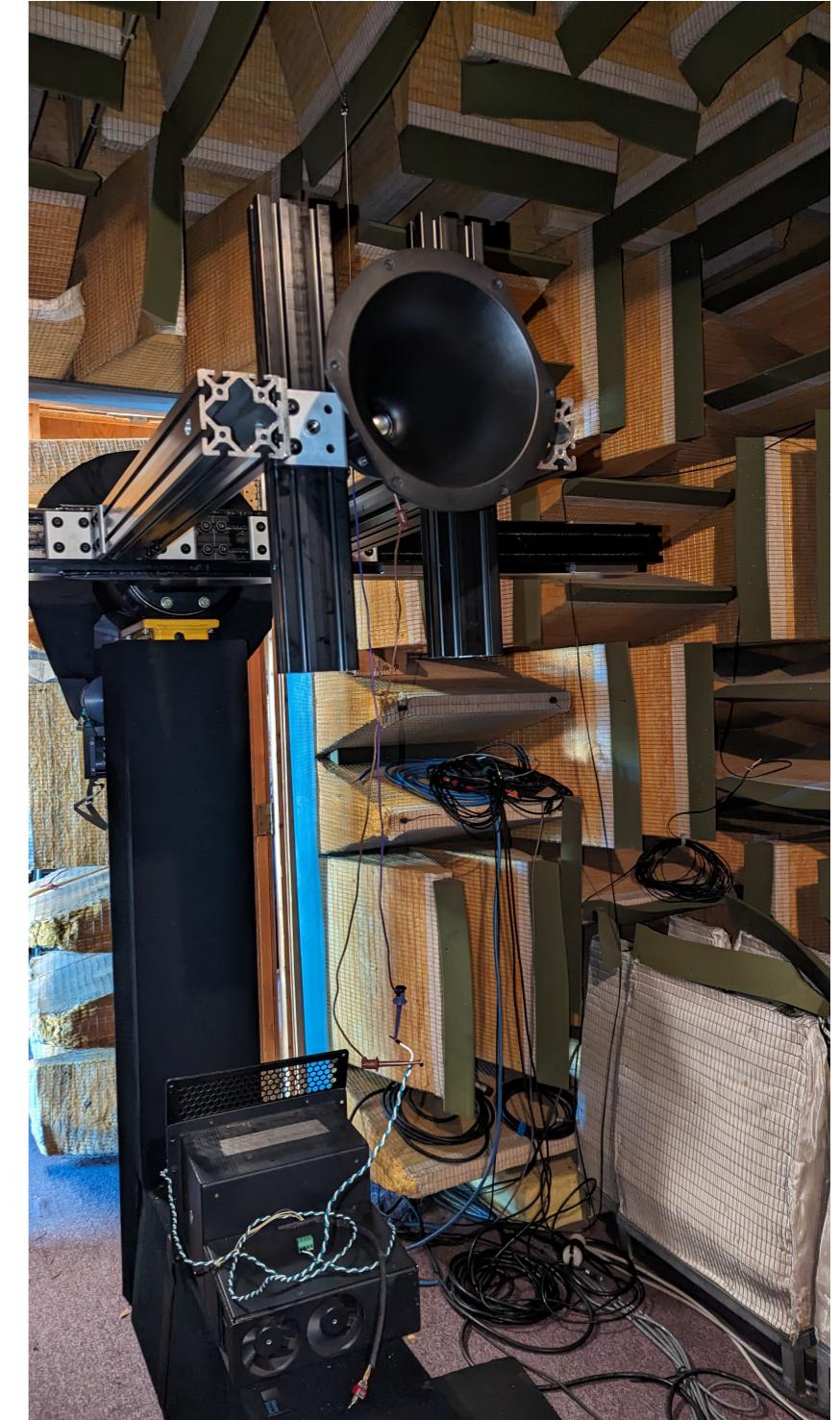
$$(-\Delta + \omega_{\pm}^2)u = f_{\pm} \quad x \in \Omega_{\pm}$$
$$[[n \cdot \nabla u]] = -mu \quad x \in \partial\Omega$$



Applications: Speaker design and modeling



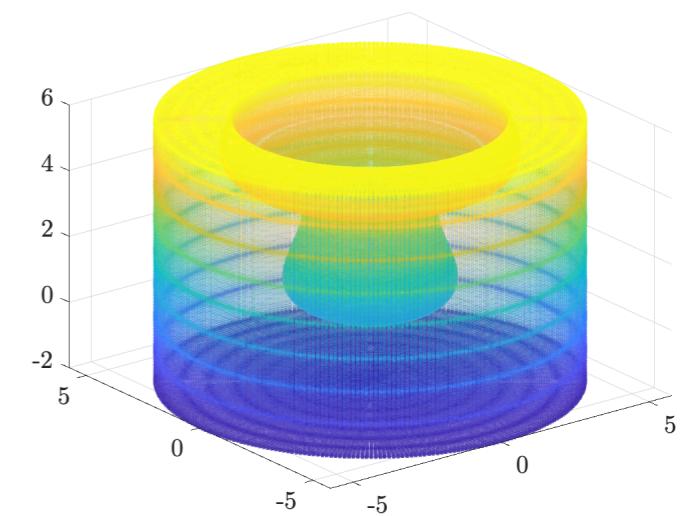
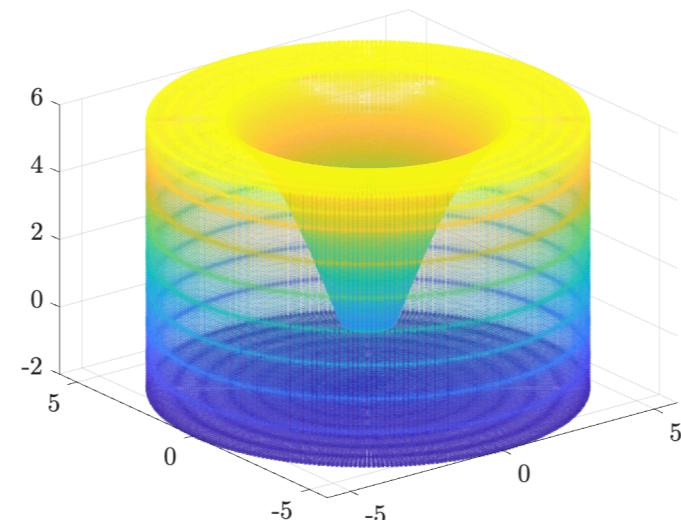
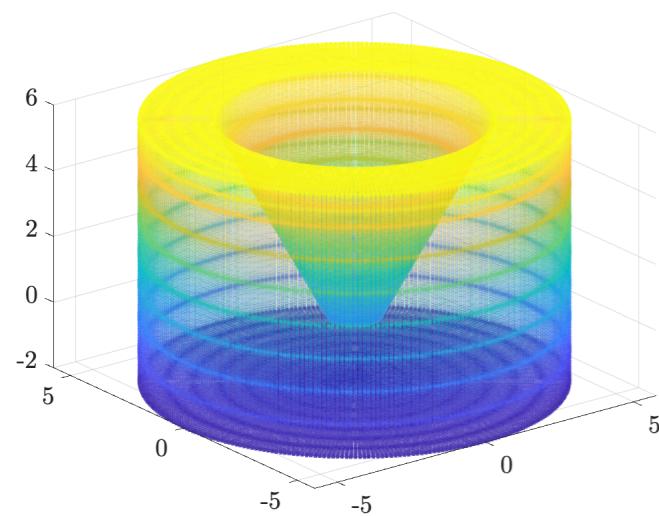
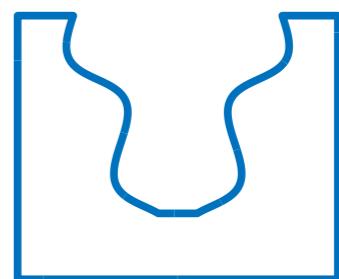
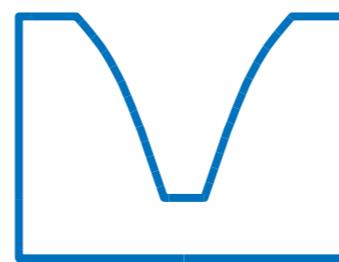
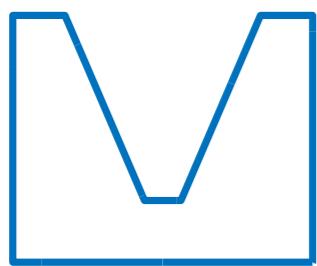
Thanks to Perrin Meyer, Meyer Sound



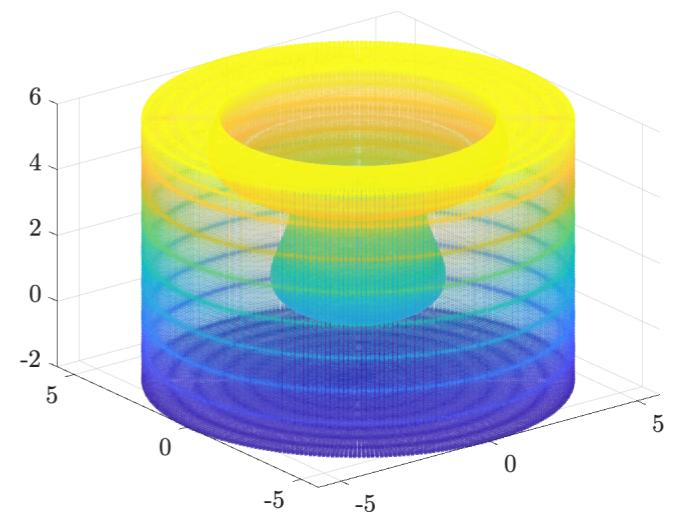
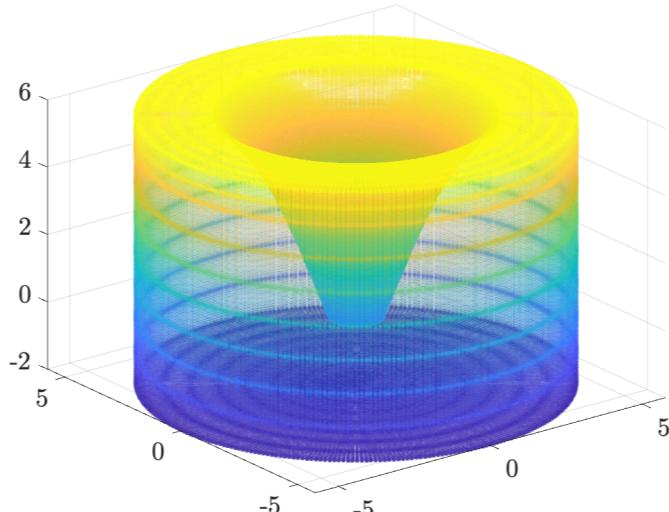
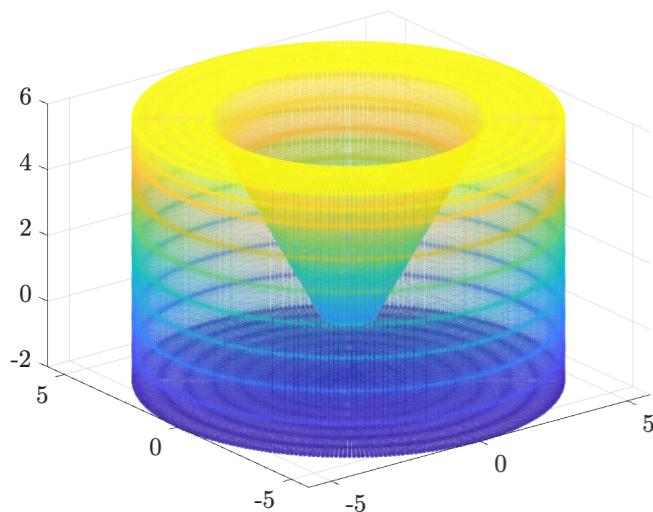
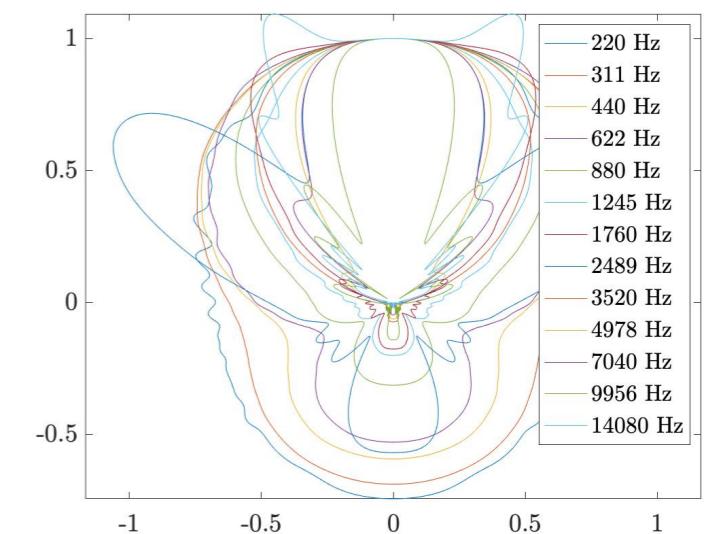
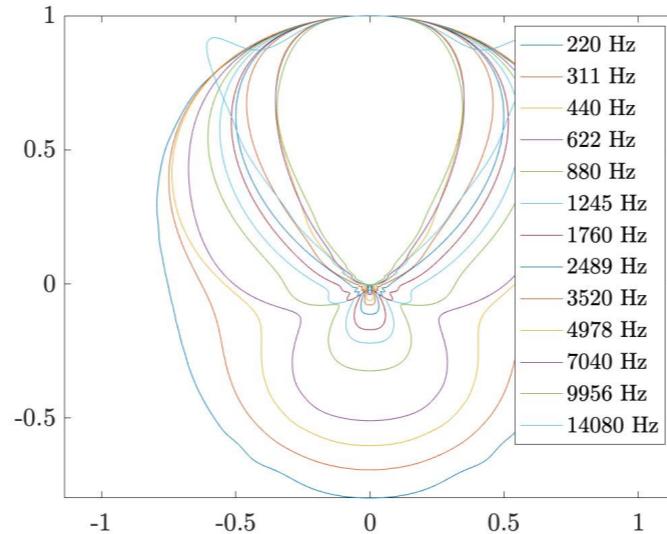
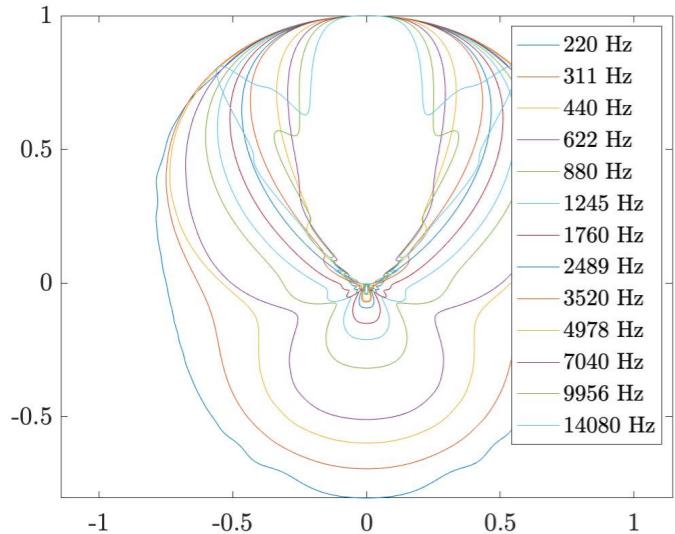
$$(\Delta + k^2)u = 0 \quad \text{in } \mathbb{R}^{2/3} \setminus \Omega$$

$$\frac{\partial u}{\partial n} = 0 \quad \text{on } \partial\Omega$$

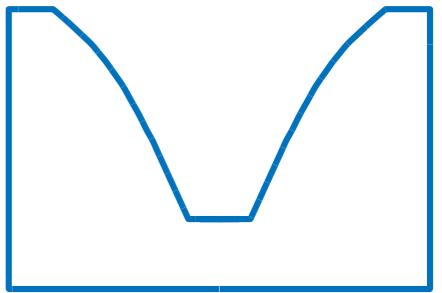
Applications: Speaker design and modeling



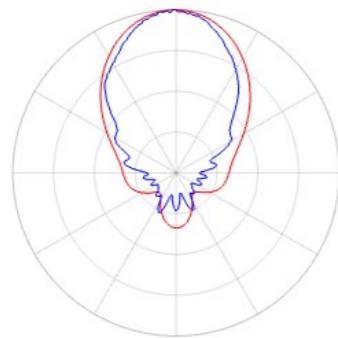
Applications: Speaker design and modeling



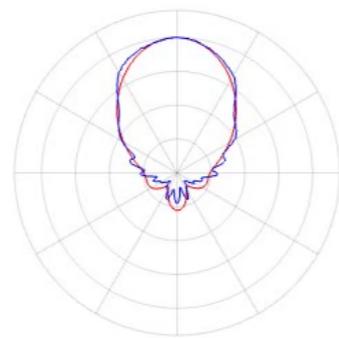
Applications: Speaker design and modeling



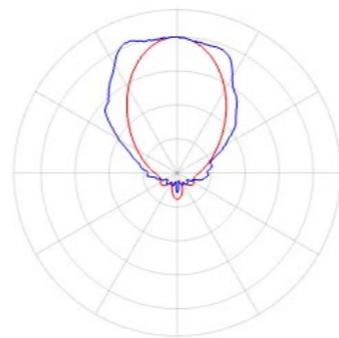
996.1 Hz



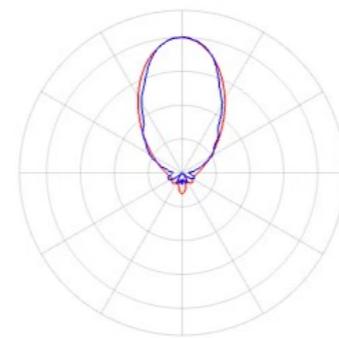
1171.9 Hz



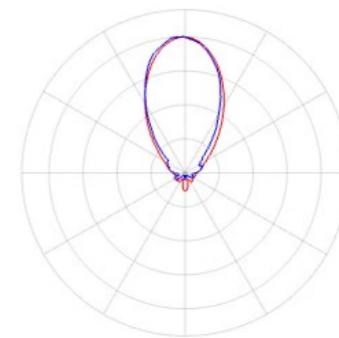
1476.6 Hz



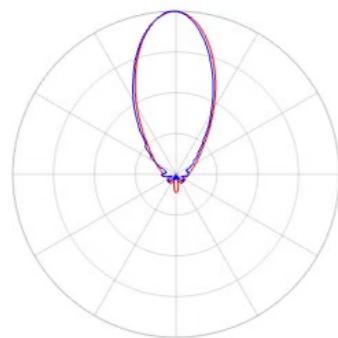
1781.2 Hz



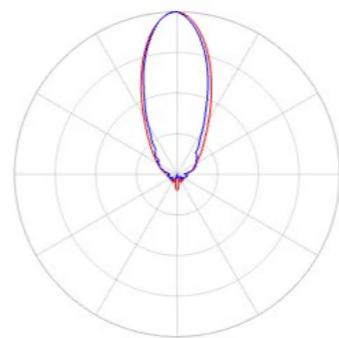
2085.9 Hz



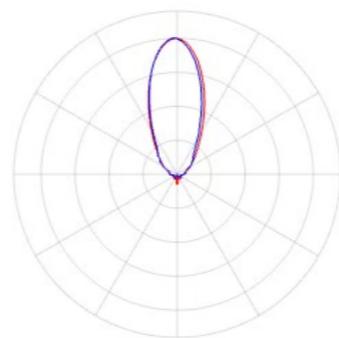
2531.2 Hz



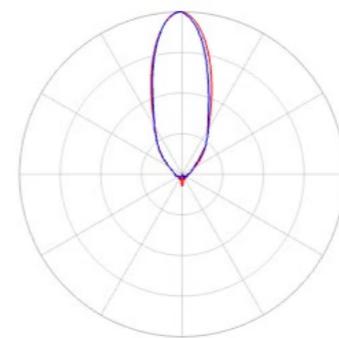
3140.6 Hz



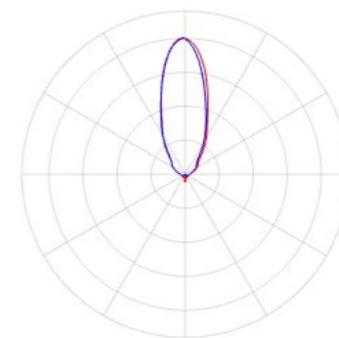
3750.0 Hz



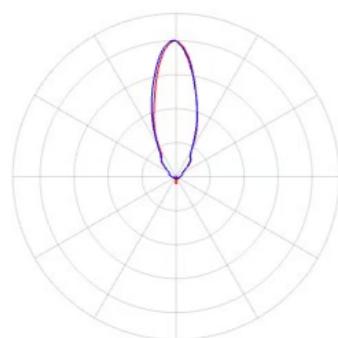
4359.4 Hz



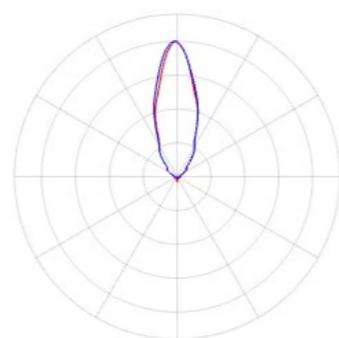
5437.5 Hz



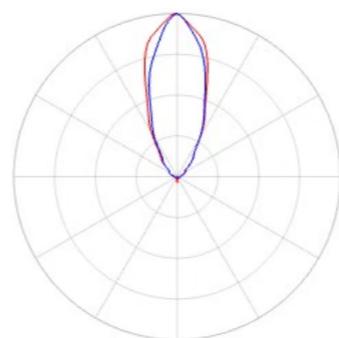
6656.2 Hz



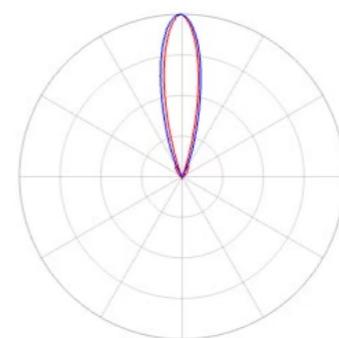
7875.0 Hz



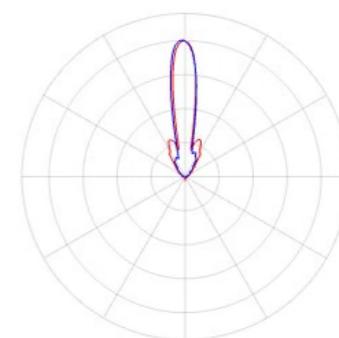
9187.5 Hz



11625.0 Hz

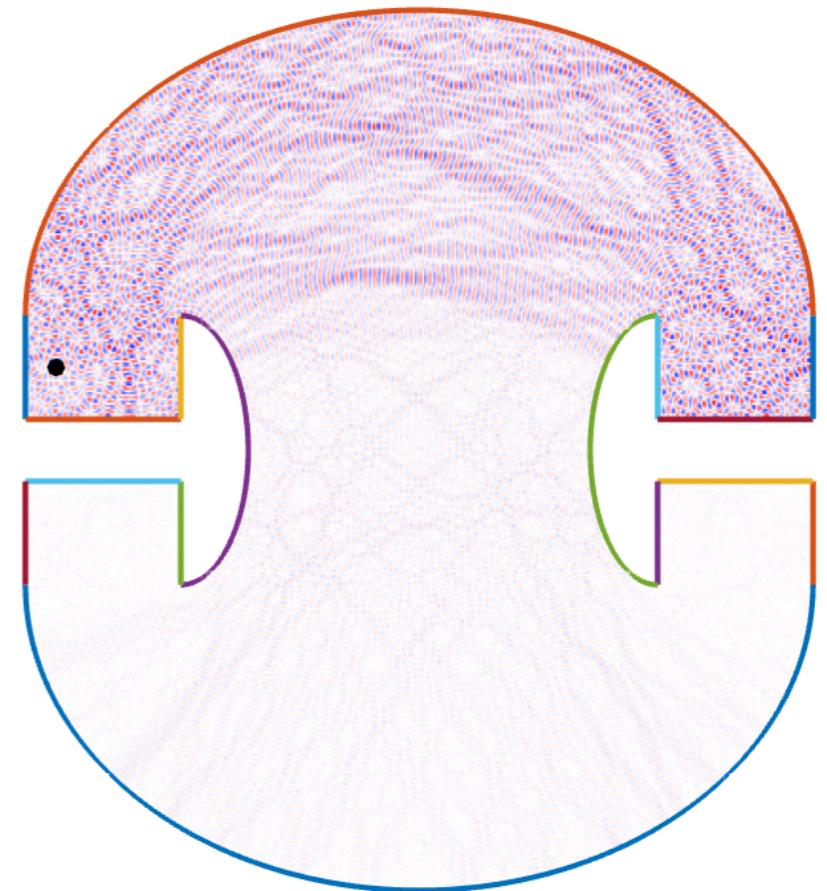


14062.5 Hz



6 steps to live the good life through integral equations

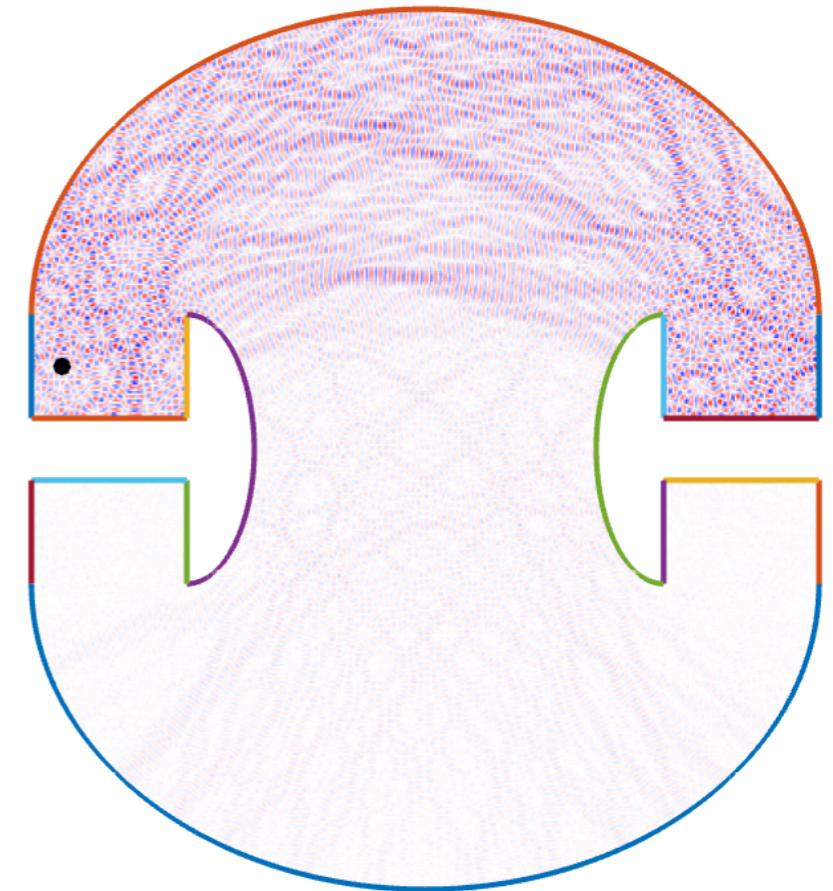
1. Identify a PDE and boundary conditions
2. Convert it into an integral equation (Lecture 2)
3. Discretize geometry (Lecture 1)
4. Discretize integral operators (Lecture 3)
5. Solve the integral equation (Lecture 4+5)
6. Post-process/recover PDE solution (Lecture 4+5)



6 step to live the good life through integral equations

1. Identify a PDE and boundary conditions

$$(\Delta + k^2)u = 0 \quad \text{in } \Omega$$
$$u = f \quad \text{on } \partial\Omega$$



$$(\Delta + k^2)u = 0 \quad \text{in } \Omega$$

$$u = f \quad \text{on } \partial\Omega$$

6 step to live the good life through integral equations

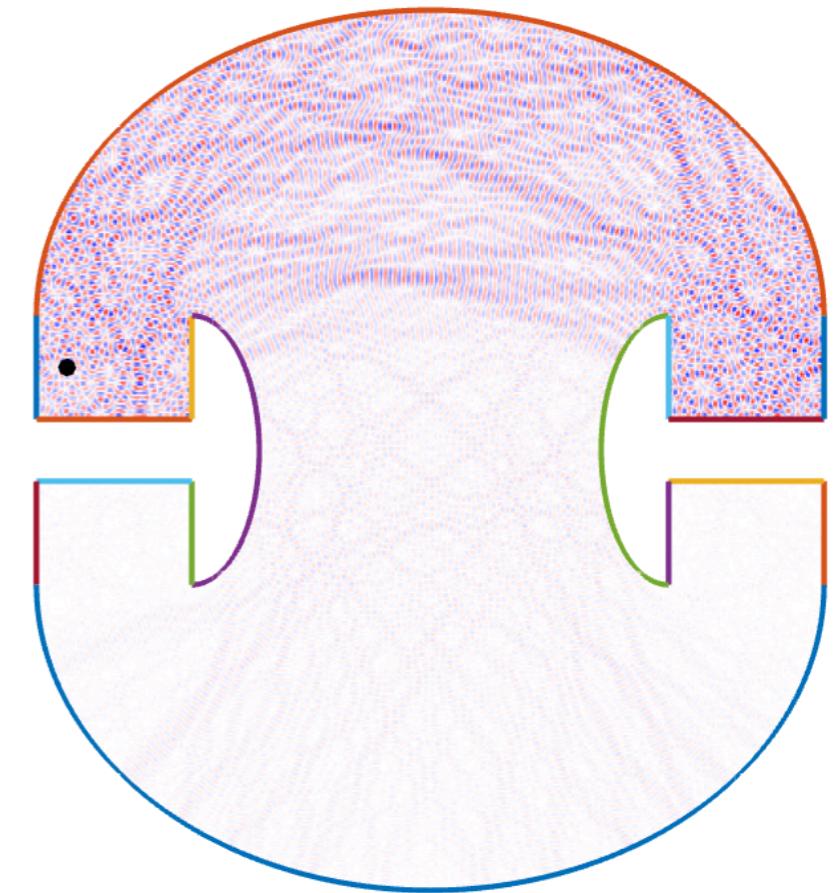
1. Identify a PDE and boundary conditions

2. Convert it into an integral equation

- Integral representations use Green's functions/fundamental solutions to represent the solution

$$(\Delta_x + k^2)G(x, y) = -\delta_{x=y}$$

$$G(x, y) = \frac{i}{4}H_0^{(1)}(k|x - y|)$$



- Information lives on the boundary alone, construct solution from bunch of Green's

functions located on the boundary, i.e. set $u(x) = \int_{\partial\Omega} G(x, y)\sigma(y)ds_y$ for $x \in \Omega$

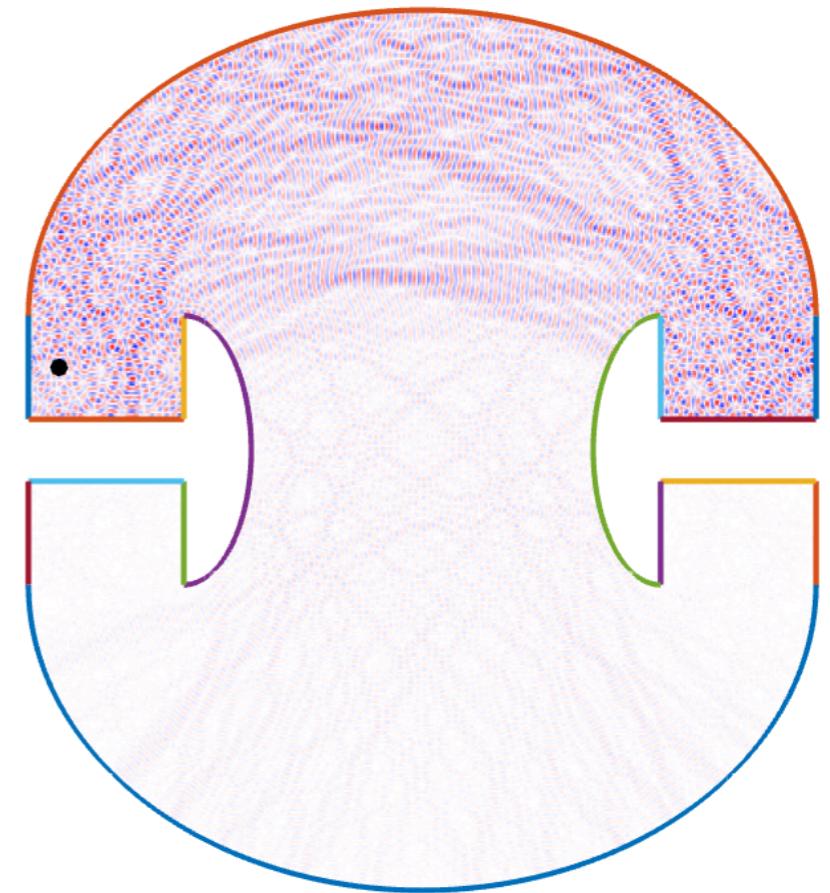
- Need to solve for σ such that $\int_{\partial\Omega} G(x, y)\sigma(y) = f(x)$ for $x \in \partial\Omega$

6 step to live the good life through integral equations

1. Identify a PDE and boundary conditions
2. Convert it into an integral equation (Lecture 2)

3. Discretize geometry

- Need a way to represent functions and integral equations on the computer, thus need to be able to interpolate functions from finite number of samples, compute their integrals...



What is function interpolation/representation?

Given:

- Discretization/sample points $\{x_j\}_{j=1}^N$
- Basis functions $\{\phi_j(x)\}_{j=1}^M$ construct an approximation
- Exact samples of a function f at discretization points $\{f(x_j)\}_{j=1}^N$

Construct:

$$\tilde{f}(x) = \sum_{j=1}^M c_j \phi_j(x) \quad \text{with} \quad \tilde{f}(x_j) = f(x_j)$$

Function types

1. Nice and periodic
2. Nice and aperiodic
3. Not so nice
 - Structure unknown: Adaptive
 - Not niceness known: Generalized chebyshev methods

Considerations for function interpolation

$$\tilde{f}(x) = \sum_{j=1}^M c_j \phi_j(x) \text{ with } \tilde{f}(x_j) = f(x_j)$$

- Accuracy
 - Small approximation error for “nice” functions, i.e. interpolant satisfies
$$\max_x |\tilde{f}(x) - f(x)| < \varepsilon$$
- Speed
 - Ability to obtain c_j given $f(x_j)$ in $O(N + M)$ or $O((N + M)\log(N + M))$ time
 - Rapid evaluation of $\tilde{f}(x)$ at new points $\Rightarrow \phi_j$ not too complicated to evaluate
- Stability