

FYS4150 - Project 1

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github.com/sindrerb/FYS4150-Collaboration

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Abstract

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I. INTRODUCTION

This project will examine different techniques for approximating the solution to a differential equation where a continuous function is known. The equation describes an electrostatic potential Φ generated by a localized charge density $\rho(\vec{r})$ and is usually described - in three dimensions - by:

$$\nabla^2 \Phi = -4\pi\rho(\vec{r}) \quad (1)$$

If $\rho(\vec{r})$ is spherical symmetric, eq. 1 may be written in a one-dimensional manner by substituting $\phi(r) = r\Phi(r)$:

$$\frac{d^2\phi(r)}{dr^2} = -4\pi r\rho(r) \quad (2)$$

By rewriting eq. 2 to a general form it reads:

$$-u''(x) = f(x) \quad (3)$$

In this specific case, the Poisson equation is solved by *Gaussian elimination* of a set of linear equations, both in a general manner and an optimized way of a specific matrix. The optimized method is later compared with another general method called *LU-decomposition*.

* A thank you or further information

II. METHODS

The methods used in this projects are the following:

- Dirichlet boundary conditions
- Numerical derivation
- Gaussian elimination
- LU-decomposition

i. Dirichlet boundary condition

Dirichlet boundary conditions - also referred to as fixed boundary condition - specifies the value of a given function on a surface $T = f(r, t)$. In a one-dimensional problem it translates to defining an interval of x - $x \in [x_{min}, x_{max}]$ - and the function values $f(x_{min}) = f_l$ and $f(x_{max}) = f_h$ at the edges of the interval.

ii. Numerical derivation

The derivative of a discrete function may be found by numerical derivation. The principle of numerical derivation is a result of Taylor expansion. By expanding a function from

a point x with a step h , two equations form depending on the direction:

$$f(x+h) = f(x) + hf'(x) + \frac{h^2}{2}f''(x) \dots \quad (4)$$

$$f(x-h) = f(x) - hf'(x) + \frac{h^2}{2}f''(x) \dots \quad (5)$$

By adding eq. 5 to eq. 4, a approximation for the second derivative is achieved.

$$f'' = \frac{f_+ - 2f + f_-}{h^2} + \frac{h^4}{6h^2}f^{IV} \quad (6)$$

Where $f_+ = f(x+h)$, $f = f(x)$, $f_- = f(x-h)$ and f^{IV} is the fourth derivative of $f(x)$. By truncating the series at the fourth derivative a small mathematical error - \mathcal{O} - appears in the order of h^2 . If a discrete funtion is introduced where $f_i = f(x_i) = f(c_0 + ih)$, eq. 6 may be rewritten to an algorithm for the numerical second derivative.

$$f''_i = \frac{f_{i+1} - 2f_i + f_{i-1}}{h^2} \quad (7)$$

In eq. 7 the mathematical error $\mathcal{O}(h^2)$ is neglected.

iii. Gaussian elimination

Gaussian elimination is a method for simplifying a set of N linear equations with n unknown variables x_i $i = 0, 1, \dots, n-1$:

$$\begin{aligned} a_{00}x_0 + a_{01}x_1 + a_{02}x_2 &= y_0 \\ a_{10}x_0 + a_{11}x_1 + a_{12}x_2 &= y_1 \\ a_{20}x_0 + a_{21}x_1 + a_{22}x_2 &= y_2 \end{aligned}$$

It is easily visualized through a matrix notation of $Ax = y$ where A and y is known.

$$\begin{bmatrix} a_{00} & a_{01} & a_{02} \\ a_{10} & a_{11} & a_{12} \\ a_{20} & a_{21} & a_{22} \end{bmatrix} \begin{bmatrix} x_0 \\ x_1 \\ x_2 \end{bmatrix} = \begin{bmatrix} y_0 \\ y_1 \\ y_2 \end{bmatrix} \quad (8)$$

Gaussian elimination is often divided into two main parts, forward and backward substitution.

Forward substitution

The forward substitution is focusing on reducing the number of variables in the set of linear equations to a minimum. In other words, row reduction is used on the matrix A to eliminate all elements a_{i1} where $i < 1$. Turning the matrix equation to $Bx = \hat{y}$:

$$\begin{bmatrix} b_{00} & b_{01} & b_{02} \\ 0 & b_{11} & b_{12} \\ 0 & b_{21} & b_{22} \end{bmatrix} \begin{bmatrix} x_0 \\ x_1 \\ x_2 \end{bmatrix} = \begin{bmatrix} \hat{y}_0 \\ \hat{y}_1 \\ \hat{y}_2 \end{bmatrix} \quad (9)$$

where \hat{y} is affected by the row reduction. The process is repeated until matrix A is transformed to an upper triangular matrix A'

$$\begin{bmatrix} a_{00} & a_{01} & a_{02} \\ 0 & a_{11} & a_{12} \\ 0 & 0 & a_{22} \end{bmatrix} \begin{bmatrix} x_0 \\ x_1 \\ x_2 \end{bmatrix} = \begin{bmatrix} \hat{y}_0 \\ \hat{y}_1 \\ \hat{y}_2 \end{bmatrix} \quad (10)$$

This set of linear equations is the basis for backward substitution.

Backward substitution

The concept of backwars substitution is to solve the the set of equations from bsnto the equation above. In the end, all elements of x is known.

iv. LU-decompostition

v. Numerical error estimate

Since we are using numerical derivation this gives us an approximation to the analytical answer. Therefore it is interesting to see how good our approximation is. A good way to do this is to look at the difference between the two.

At small step lenghts (h) we will have a good approximation if the theori is correct and therefore it is convenient too look at the logaritme of the difference we also use the absolute value since we dont care if we are over or under the analytical answer. To avoid the logaritme of zero we also devide by the analytical value.

So we get the relative error ϵ and for each step we get:

$$\varepsilon_i = \log \left(\left| \frac{u_i - v_i}{v_i} \right| \right) \quad (11)$$

Here u_i is the numerical value and v_i is the analytical value at step i . And \log is the base 10 logarithm.

III. IMPLEMENTATION

By discretizing the simplified and generalized Poisson equation (eq. 6) in steps of h , we may approximate eq. 6 with eq. 12 where v_i is the discrete values of the continuum $u(x)$.

$$-\frac{v_{i+1} - 2v_i + v_{i-1}}{h^2} = f_i \quad (12)$$

The equation may be rewritten into a linear equation

$$av_{i-1} + bv_i + cv_{i+1} = \tilde{b}_i$$

where $a = -1$, $b = 2$, $c = -1$ and $\tilde{b}_i = f_i h^2$. By introducing dirichlet boundary conditions, $v_0 = v_{n+1} = 0$, the linear equations may be written in terms of matrix multiplication without loss of information. This results in $Av = \tilde{b}$:

$$\begin{bmatrix} b & c & 0 & 0 & 0 & \cdots & 0 \\ a & b & c & 0 & 0 & \cdots & 0 \\ 0 & a & b & c & 0 & \cdots & 0 \\ 0 & 0 & a & b & c & \cdots & 0 \\ \vdots & \vdots & \vdots & \vdots & \vdots & \ddots & c \\ 0 & 0 & 0 & 0 & 0 & a & b \end{bmatrix} \begin{bmatrix} v_1 \\ v_2 \\ v_3 \\ \vdots \\ v_{n-1} \\ v_n \end{bmatrix} = \begin{bmatrix} \tilde{b}_0 \\ \tilde{b}_1 \\ \tilde{b}_2 \\ \vdots \\ \tilde{b}_{n-2} \\ \tilde{b}_{n-1} \end{bmatrix}$$

The problem is now solvable by both Gaussian elimination and LU-decomposition. For all programs, divided in task b , c and d see the github repository:

github.com/sindrerb/FYS4150-Collaboration