Scalable solvers for the 3D non-Newtonian Stokes problem in ice flow modeling

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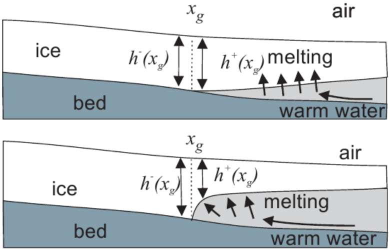
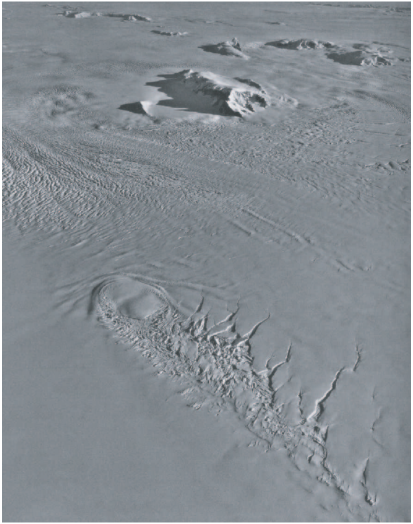
Why do we need 3D Stokes?





Non-Newtonian Stokes system

- Strong form: Find $(\boldsymbol{u}, p) \in \boldsymbol{\mathcal{V}}_D \times \mathcal{P}$ such that

$$\begin{aligned} -\nabla\cdot(\eta D\boldsymbol{u}) + \nabla p - \boldsymbol{f} &= 0 \\ \nabla\cdot\boldsymbol{u} &= 0 \end{aligned}$$

where

$$\begin{aligned} D\boldsymbol{u} &= \tfrac{1}{2}\left(\nabla\boldsymbol{u} + (\nabla\boldsymbol{u})^T\right) \\ \gamma(D\boldsymbol{u}) &= \tfrac{1}{2} D\boldsymbol{u} : D\boldsymbol{u} \\ \eta(\gamma) &= B(\Theta, \dots)\big(\epsilon + \gamma\big)^{\frac{\mathfrak{p}-2}{2}}, \quad \mathfrak{p} = 1 + \tfrac{1}{\mathfrak{n}} \approx \tfrac{4}{3} \end{aligned}$$

with boundary conditions

$$(D\boldsymbol{u} - p\mathbf{1})\cdot\boldsymbol{n} = \begin{cases} \mathbf{0} & \text{free surface} \\ -\rho_w z\boldsymbol{n} & \text{ice-ocean interface} \end{cases}$$

$$\boldsymbol{u} = \mathbf{0} \qquad \text{frozen bed}, \Theta < \Theta_0$$

$$\left.\begin{aligned} \boldsymbol{u}\cdot\boldsymbol{n} &= \boldsymbol{g}_{\mathsf{melt}}(T\boldsymbol{u}, \dots) \\ T(D\boldsymbol{u} - p\mathbf{1})\cdot\boldsymbol{n} &= \boldsymbol{g}_{\mathsf{slip}}(T\boldsymbol{u}, \dots) \end{aligned}\right\} \text{nonlinear slip}, \Theta \geq \Theta_0$$

Other forms

- Minimization form: Find $\boldsymbol{u} \in \boldsymbol{\mathcal{V}}_D$ which minimizes
$$\mathcal{I}(\boldsymbol{u}) = \int_\Omega |D\boldsymbol{u}|^{\mathfrak{p}} - \boldsymbol{f} \cdot \boldsymbol{u}$$
subject to
$$\nabla \cdot \boldsymbol{u} = 0$$
- Weak form: Find $(\boldsymbol{u}, p) \in \boldsymbol{\mathcal{V}}_D \times \mathcal{P}$ such that
$$\int_\Omega \eta D\boldsymbol{v} : D\boldsymbol{u} - p\nabla \cdot \boldsymbol{v} - q\nabla \cdot \boldsymbol{u} - \boldsymbol{f} \cdot \boldsymbol{v} \\ - \int_{\partial\Omega} \boldsymbol{g}(T\boldsymbol{u}) \cdot \boldsymbol{v} = 0 \quad \forall (\boldsymbol{v}, q) \in \boldsymbol{\mathcal{V}}_0 \times \mathcal{P}$$
- Slip
$$\boldsymbol{g}_{\mathsf{slip}}(T\boldsymbol{u}) = \beta_{\mathfrak{m}}(\dots)|T\boldsymbol{u}|^{\mathfrak{m}-1} T\boldsymbol{u}$$
Navier $\mathfrak{m} = 1$, Weertman $\mathfrak{m} \approx \frac{1}{3}$, Coulomb $\mathfrak{m} = 0$.

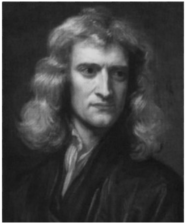
Newton iteration

- Standard form of a nonlinear system

$$F(x) = 0$$

- Iteration

$$\begin{aligned} \text{Solve:} \quad & J(x^n)s^n = -F(x^n) \\ \text{Update:} \quad & x^{n+1} \leftarrow x^n + s^n \end{aligned}$$



Stokes problem

$$F(\boldsymbol{u}, p) \sim \int_\Omega \eta D\boldsymbol{v} : D\boldsymbol{u} - p\nabla\cdot\boldsymbol{v} - q\nabla\cdot\boldsymbol{u} - \boldsymbol{f}\cdot\boldsymbol{v} = 0 \quad \forall(\boldsymbol{v}, q)$$

$$J(\boldsymbol{w})\left[\begin{smallmatrix}\boldsymbol{u}\\ p\end{smallmatrix}\right] \sim \int_\Omega \eta D\boldsymbol{v} : D\boldsymbol{u} + \eta'(D\boldsymbol{v} : D\boldsymbol{w})(D\boldsymbol{w} : D\boldsymbol{u})$$

$$- p\nabla\cdot\boldsymbol{v} - q\nabla\cdot\boldsymbol{u}$$

$$J(\boldsymbol{w}) = \begin{bmatrix} A(\boldsymbol{w}) & B^T \\ B & \end{bmatrix}$$

Matrices and Preconditioners

Definition (Matrix)

A matrix is a linear transformation between finite dimensional vector spaces.

Definition (Forming a matrix)

Forming or assembling a matrix means defining it's action in terms of entries (usually stored in a sparse format).

Definition (Preconditioner)

A preconditioner $\mathscr{P}$ is a method for constructing a matrix (just a linear function, not assembled!) $P^{-1} = \mathscr{P}(\hat{J})$ using information $\hat{J}$, such that $P^{-1}J$ (or JP^{-1}) has favorable spectral properties.

Left preconditioning in a Krylov iteration

$$(P^{-1}J)x = P^{-1}b$$

$$\{P^{-1}b, (P^{-1}J)P^{-1}b, (P^{-1}J)^2P^{-1}b, \dots\}$$

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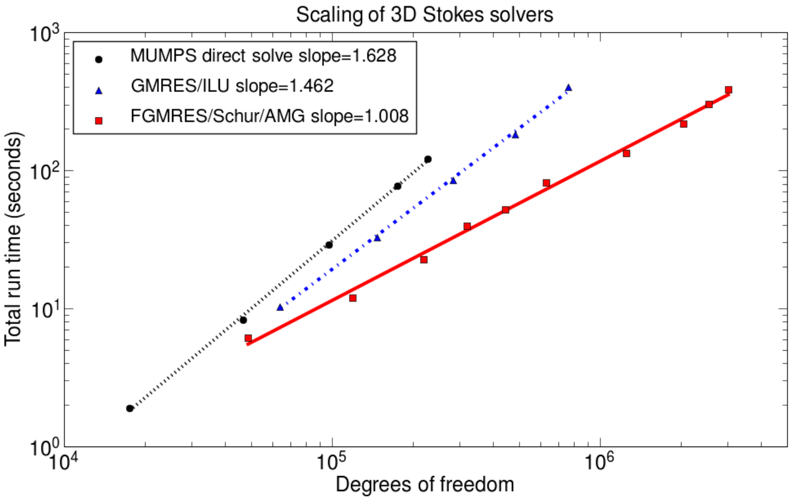
Normal preconditioners fail for indefinite problems



Stokes

Weak form of the Newton step

Find $(\boldsymbol{u}, p)$ such that

$$\int_\Omega \eta D\boldsymbol{v} : D\boldsymbol{u} + \eta'(D\boldsymbol{v} : D\boldsymbol{w})(D\boldsymbol{w} : D\boldsymbol{u})$$
$$- p\nabla \cdot \boldsymbol{v} - q\nabla \cdot \boldsymbol{u} = -v \cdot F(\boldsymbol{w}) \qquad \forall(\boldsymbol{v}, q)$$

Matrix

$$Jx = J(\boldsymbol{w}) = \begin{bmatrix} A(\boldsymbol{w}) & B^T \\ B & \end{bmatrix} \begin{pmatrix} u \\ p \end{pmatrix} = - \begin{pmatrix} F_u(\boldsymbol{w}) \\ 0 \end{pmatrix}$$

Block factorization

$$\begin{bmatrix} A & B^T \\ B & \end{bmatrix} = \begin{bmatrix} 1 & \\ BA^{-1} & 1 \end{bmatrix} \begin{bmatrix} A & B^T \\ & S \end{bmatrix} = \begin{bmatrix} A & \\ B & S \end{bmatrix} \begin{bmatrix} 1 & A^{-1}B^T \\ & 1 \end{bmatrix}$$

where the Schur complement is

$$S = -BA^{-1}B^T.$$

Properties of the Schur complement

Block factorization

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where

$$S = -BA^{-1}B^T.$$

- S is symmetric negative definite if A is SPD and B has full rank (discrete inf-sup condition)
- S is dense
- We only need to multiply B, B^T with vectors.
- We need preconditioners for A and S.
- Any definite preconditioner can be used for A.
- It's not obvious how to precondition S, more on that later.

Reduced factorizations are sufficient

Theorem (GMRES convergence)

GMRES applied to

$$Kx = b$$

converges in n steps for all right hand sides if the minimal polynomial of K has degree n.
(There exists a polynomial π_n such that $\pi_n(K) = 0$ and $\pi_n(0) = 1$.)

A lower-triangular preconditioner

Left precondition J:

$$\begin{aligned} K = P^{-1}J &= \begin{bmatrix} A & \\ B & S \end{bmatrix}^{-1} \begin{bmatrix} A & B^T \\ B & \end{bmatrix} \\ &= \begin{bmatrix} A^{-1} & \\ -S^{-1}BA^{-1} & S^{-1} \end{bmatrix} \begin{bmatrix} A & B^T \\ B & \end{bmatrix} = \begin{bmatrix} 1 & A^{-1}B^T \\ & 1 \end{bmatrix} \end{aligned}$$

Since $(K-1)^2 = 0$, GMRES converges in at most 2 steps.

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Preserving symmetry for MINRES

P must be SPD

$$P^{-1} = \begin{bmatrix} A & \\ & -S \end{bmatrix}^{-1}$$

$$K = P^{-1}J = \begin{bmatrix} A^{-1} & \\ & -S^{-1} \end{bmatrix} \begin{bmatrix} A & B^T \\ B & \end{bmatrix} = \begin{bmatrix} 1 & A^{-1}B^T \\ -S^{-1}B & \end{bmatrix}$$

$$\left(K - \frac{1}{2}\right)^2 = \begin{bmatrix} \frac{1}{4} - A^{-1}B^T S^{-1} B & \\ & \frac{5}{4} \end{bmatrix}$$

$$\left(K - \frac{1}{2}\right)^2 - \frac{1}{4} = \begin{bmatrix} -A^{-1}B^T S^{-1} B & \\ & 1 \end{bmatrix}$$

Now $Q = -A^{-1}B^T S^{-1} B$ is a projector ($Q^2 = Q$) so

$$\left[\left(K - \frac{1}{2}\right)^2 - \frac{1}{4}\right]^2 = \left(K - \frac{1}{2}\right)^2 - \frac{1}{4}$$

Rearranging, $K(K-1)(K^2 - T - 1) = 0$. MINRES converges in at most 3 iterations.

Preconitioning the Schur complement

- $S = -BA^{-1}B^T$ is dense so we can't form it, we need S^{-1}.

Physics-based commutator: anisotropic pressure diffusion

$$\boldsymbol{v}^T A(\boldsymbol{w})\boldsymbol{u} \sim \int (D\boldsymbol{v})^T \left[\eta \mathbf{1} + \eta' D\boldsymbol{w} \otimes D\boldsymbol{w}\right] D\boldsymbol{u}$$

- We would like to find an operator A_p such that
$$-S = BA^{-1}B^T \approx BB^T A_p^{-1} =: P_S$$
so that
$$P_S^{-1} = A_p(BB^T)^{-1}$$
- Note
$$BB^T \sim (-\nabla \cdot)\nabla = -\Delta$$
corresponds to a Laplacian in the pressure space (multigrid).
- If $\eta', \nabla\eta \ll 1$ then $A_p \sim -\eta\Delta$ so $P_S^{-1} = \eta\mathbf{1}$

Least squares commutator

- Schur complement

$$S = -BA^{-1}B^T$$

Suppose B is square and nonsingular. Then

$$S^{-1} = -B^{-T}AB^{-1}.$$

B is not square, replace B^{-1} with Moore-Penrose pseudoinverse

$$B^\dagger = B^T(BB^T)^{-1}, \qquad (B^T)^\dagger = (BB^T)^{-1}B.$$

Then

$$P_S^{-1} = -(BB^T)^{-1}BAB^T(BB^T)^{-1}.$$

- Requires 2 Poisson preconditioners for $(BB^T)^{-1}$ per iteration
- Better with scaling, from mass matrices and effective viscosity (Elman et al. 2006, May & Moresi 2008)