

On non-Hermitian positive (semi)definite linear algebraic systems arising from dHDAE systems

Saturday, 11 June 2022 09:15 (30 minutes)

It is well known that every matrix $A \in \mathbb{C}^{n \times n}$ can be split into its Hermitian and skew-Hermitian parts, i.e., $A = H + S$, $H = \frac{1}{2}(A + A^*)$, $S = \frac{1}{2}(A - A^*)$, so that $H = H^*$ and $S = -S^*$. This simple, yet fundamental observation has many consequences. For instance, if A is a matrix, then H is Hermitian and S is skew-Hermitian. In the case of real matrices, H is symmetric and S is skew-symmetric. The eigenvalues of H are real, and the eigenvalues of S are purely imaginary. The eigenvalues of A are the eigenvalues of H plus the eigenvalues of S . This is a simple, yet fundamental observation that has many consequences. For instance, if A is a matrix, then H is Hermitian and S is skew-Hermitian. In the case of real matrices, H is symmetric and S is skew-symmetric. The eigenvalues of H are real, and the eigenvalues of S are purely imaginary. The eigenvalues of A are the eigenvalues of H plus the eigenvalues of S .

In the first part of this talk we will discuss an important class of practically relevant applications where the splitting $A = H + S$ occurs naturally and has a physical meaning. These applications arise from energy-based modeling using differential algebraic equations (DAE) systems in dissipative Hamiltonian (dH) form, or shortl

In the second part we will study the linear algebraic systems arising in this context, and their solution by Krylov subspace methods. The (non-Hermitian) matrices A that occur are positive definite or positive semidefinite. In the positive definite case we can solve the linear algebraic systems using Krylov subspace methods based on efficient three-term recurrences. Such methods were already derived by Widlund [6] (based on earlier work of Concus and Golub [3]) and Rapoport [5] in the late 1970s. These methods are not widely used or known, and we will therefore summarize the most important facts about their implementation and their mathematical properties. The semidefinite case can be challenging and requires additional techniques to identify and deal with the “singular part” of the matrix, while the “positive definite part” can still be treated with the three-term recurrence methods. We will illustrate the performance of the iterative methods and compare them with (preconditioned) GMRES on several computed examples.

The talk is based on joint work with Candan Gdc, Volker Mehrmann, and Daniel B. Szyld [4].

References

- [1] M. Benzi, G. H. Golub and J. Liesen, Numerical solution of saddle point problems Acta Numer., 14 (2005), pp. 1–137.
- [2] M. Benzi and V. Simoncini, On the eigenvalues of a class of saddle point matrices, Numer. Math., 103 (2006), pp. 173–196.
- [3] P. Concus and G. H. Golub, A generalized conjugate gradient method for nonsymmetric systems of linear equations, in Computing methods in applied sciences and engineering (Second Internat. Sympos., Versailles, 1975), Part 1, Roland Glowinski and Jaques-Louis Lions, eds., vol. 134 of Lecture Notes in Econom. and Math. Systems, Springer, Berlin, 1976, pp. 56–65.
- [4] C. Gdc, J. Liesen, V. Mehrmann, and D. B. Szyld, On non-Hermitian positive (semi)definite linear algebraic systems arising from dissipative Hamiltonian DAEs, arXiv:2111.05616, 2021.
- [5] D. Rapoport, A Nonlinear Lanczos Algorithm and the Stationary Navier-Stokes Equation, PhD thesis, Department of Mathematics, Courant Institute, New York University, 1978.
- [6] O. Widlund, A Lanczos method for a class of nonsymmetric systems of linear equations, SIAM J. Numer. Anal., 15 (1978), pp. 801–812.

Presenter: LIESEN, Jrg (TU Berlin)