

## Abstract

An abstract is a brief summary of the paper's contributions, written for experts. Authors are anonymized for double-blind review.

## 1 Introduction.

An introduction is a gentler description and summary of the paper than the abstract, written for non-experts. It describes the paper's concepts, contribution, context and significance.

**1.1 Problem Specification.** In this paper, we consider the solution of the  $N \times N$  linear system

$$(1.1) \quad Ax = b$$

where  $A$  is large, sparse, symmetric, and positive definite. We consider the direct solution of eq. (1.1) by means of general sparse Gaussian elimination. In such a procedure, we find a permutation matrix  $P$ , and compute the decomposition

$$PAP^t = LDL^t$$

where  $L$  is unit lower triangular and  $D$  is diagonal.

## 2 Design Considerations.

Several good ordering algorithms (nested dissection and minimum degree) are available for computing  $P$  [3, 7]. Since our interest here does not focus directly on the ordering, we assume for convenience that  $P = I$ , or that  $A$  has been preordered to reflect an appropriate choice of  $P$ .

Our purpose here is to examine the nonnumerical complexity of the sparse elimination algorithm given in [1]. As was shown there, a general sparse elimination scheme based on the bordering algorithm requires less storage for pointers and row/column indices than more traditional implementations of general sparse elimination. This is accomplished by exploiting the m-tree, a particular spanning tree for the graph of the filled-in matrix.

**THEOREM 2.1.** *The method was extended to three dimensions. For the standard multigrid coarsening (in which, for a given grid, the next coarser grid has  $1/8$  as many points), anisotropic problems require plane relaxation to obtain a good smoothing factor.*

Our purpose here is to examine the nonnumerical complexity of the sparse elimination algorithm given in [1]. As was shown there, a general sparse elimination scheme based on the bordering algorithm requires less storage for pointers and row/column indices than more traditional implementations of general sparse elimination; see Thm. 2.1. This is accomplished by exploiting the m-tree, a particular spanning tree for the graph of the filled-in matrix. Several good ordering algorithms (nested dissection and minimum degree) are available for computing  $P$  [3, 7]. Since our interest here does not focus directly on the ordering, we assume for convenience that  $P = I$ , or that  $A$  has been preordered to reflect an appropriate choice of  $P$ .

*Proof.* In this paper we consider two methods. The first method is basically the method considered with two differences: first, we perform plane relaxation by a two-dimensional multigrid method, and second, we use a slightly different choice of interpolation operator, which improves performance for nearly singular problems. In the second method coarsening is done by successively coarsening in each of the three independent variables and then ignoring the intermediate grids; this artifice simplifies coding considerably.  $\square$

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**DEFINITION 2.1.** We describe the two methods in section 2. In section 2.1 we discuss some remaining details.

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\*The full version of the paper can be accessed at [redacted-url](#)

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**LEMMA 2.1.** *We discuss first the choice for  $I_{k-1}^k$  which is a generalization. We assume that  $G^{k-1}$  is obtained from  $G^k$  by standard coarsening; that is, if  $G^k$  is a tensor product grid  $G_x^k \times G_y^k \times G_z^k$ ,  $G^{k-1} = G_x^{k-1} \times G_y^{k-1} \times G_z^{k-1}$ , where  $G_x^{k-1}$  is obtained by deleting every other grid point of  $G_x^k$  and similarly for  $G_y^k$  and  $G_z^k$ .*

To our knowledge, the m-tree previously has not been applied in this fashion to the numerical factorization, but it has been used, directly or indirectly, in several optimal order algorithms for computing the fill-in during the symbolic factorization phase [4, 5, 6, 7, 8, 9, 10]. In section 2.1, we analyze the complexity of the old and new approaches to the intersection problem for the special case of an  $n \times n$  grid ordered by nested dissection. The special structure of this problem allows us to make exact estimates of the complexity. To our knowledge, the m-tree previously has not been applied in this fashion to the numerical factorization, but it has been used, directly or indirectly, in several optimal order algorithms for computing the fill-in during the symbolic factorization phase [4, 5, 6, 7, 8, 9, 10].

In section 2, we review the bordering algorithm, and introduce the sorting and intersection problems that arise in the sparse formulation of the algorithm. In section 2.1, we analyze the complexity of the old and new approaches to the intersection problem for the special case of an  $n \times n$  grid ordered by nested dissection. The special structure of this problem allows us to make exact estimates of the complexity. To our knowledge, the m-tree previously has not been applied in this fashion to the numerical factorization, but it has been used, directly or indirectly, in several optimal order

Figure 1: This is a blank figure.

algorithms for computing the fill-in during the symbolic factorization phase [4, 5, 6, 7, 8, 9, 10].

For the old approach, we show that the complexity of the intersection problem is  $O(n^3)$ , the same as the complexity of the numerical computations. For the new approach, the complexity of the second part is reduced to  $O(n^2(\log n)^2)$ .

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We show a blank figure in fig. 1.

**2.1 Robustness.** We do not attempt to present an overview here, but rather attempt to focus on those results that are relevant to our particular algorithm; see fig. 1. This section assumes prior knowledge of the role of graph theory in sparse Gaussian elimination;

surveys of this role are available in [7, 3]. More general discussions of elimination trees are given in [4, 5, 6, 10]. Thus, at the  $k$ th stage, the bordering algorithm consists of solving the lower triangular system

$$(2.2) \quad L_{k-1}v = c$$

and setting

$$(2.3) \quad \ell = D_{k-1}^{-1}v,$$

$$(2.4) \quad \delta = \alpha - \ell^t v.$$

### 3 Algorithm

We provide some pseudocode in Algorithm 3.1.

ALGORITHM 3.1. (DETERMINISTIC-MPS) maximal Poisson-disk sampling

**Require:** Rectangular grid  $\mathcal{G}$  of whole grid squares

**Require:** Flag if domain is periodic: **True** or **False**

**Ensure:** Maximal Poisson-disk sampling of rectangle

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function DETERMINISTIC-MPS( $\mathcal{G}$ )
  // Initialize Grid  $\mathcal{G}$ 
3:  for  $g \in \mathcal{G}$  do
     $g.\text{point} = (u, v)$  uniform random in square
     $g.\text{time} = Ae^{-Aw}$ , rand  $w$ , expovariate in area
6:   $g.\text{scooped-square} = \text{square polygon } g$ 
  end for
  Global pre-pass heuristic
9:  // Find locally-early squares
  for  $g \in \mathcal{G}$  and  $h \in \text{neighbors}(g)$  do
    increment #antecedents of  $g$  or  $h$  (later)
12: end for
  for  $g \in \mathcal{G}$  do
    EarlySquares.add( $g$  if no antecedents)
15: end for
  // Accept samples and update
  repeat
18:   $g = \text{EarlySquares.pop}()$   $\triangleright$  any order
    accept  $g.\text{point}$  as Poisson-disk sample
    for  $h \in \text{neighbors}(g)$  do
21:      decrement  $h.\text{antecedents}$ 
         $\triangleright$  since  $g$  no longer blocks  $h$ 
    // resample candidates in disk( $g.\text{point}$ )
24:  if  $h.\text{point} \in \text{disk}(g.\text{point})$  then
     $h.\text{scooped-square} -= \text{disk}(g.\text{point})$ 
    if  $h.\text{scooped-square}$  is empty then
27:       $h.\text{time} = \infty$ 
    else
    trim chocks of  $h.\text{scooped-square}$ 
30:    triangulate remaining polygon
     $U \in \{\text{chocks, triangles}\}$  by area
     $h.\text{point} \in U$  uniform by area
33:     $h.\text{time} += \text{expovar}(\text{A}(h.\text{scooped-square}))$ 

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    end if
    for  $s \in \text{neighbors}(h)$  do
      if  $h$  is later than  $s$ , but was earlier
36:      then
        increment  $h.\text{antecedents}$ 
        decrement  $s.\text{antecedents}$ 
39:      if then  $s$  has no antecedents
        EarlySquares.add(  $s$  )
      end if
42:    end if
    end for
  end if
45:  if then  $h$  has no antecedents
    EarlySquares.add(  $h$  )
  end if
48:  end for
until EarlySquares == empty
end function

```

### 4 Results.

We do not attempt to present an overview here, but rather attempt to focus on those results that are relevant to our particular algorithm, Algorithm 3.1.

**4.1 Versatility.** The special structure of this problem allows us to make exact estimates of the complexity. For the old approach, we show that the complexity of the intersection problem is  $O(n^3)$ , the same as the complexity of the numerical computations [3, 9]. For the new approach, the complexity of the second part is reduced to  $O(n^2(\log n)^2)$ .

To our knowledge, the m-tree previously has not been applied in this fashion to the numerical factorization, but it has been used, directly or indirectly, in several optimal order algorithms for computing the fill-in during the symbolic factorization phase [4, 5, 6, 7, 8, 9, 10]. In section 2.1, we analyze the complexity of the old and new approaches to the intersection problem for the special case of an  $n \times n$  grid ordered by nested dissection. The special structure of this problem allows us to make exact estimates of the complexity. To our knowledge, the m-tree previously has not been applied in this fashion to the numerical factorization, but it has been used, directly or indirectly, in several optimal order algorithms for computing the fill-in during the symbolic factorization phase [4, 5, 6, 7, 8, 9, 10].

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