

# Dispersion reduction schemes for the 3D acoustic wave equation



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## Key Concepts

**PDE Inverse Problems:** Inverse problems involve numerically reconstructing some aspect of a partial differential equation (PDE) based on known solutions of the equation. A common method is to use **Finite Difference (FD)** schemes as they are flexible, robust, and easy to implement.

**Numerical Dispersion:** Numerical Dispersion occurs when using FD schemes to approximate PDEs due to computing a continuous equation in a discrete manor. This is especially prevalent at high frequencies.

## 3D Acoustic wave equation:

$$c^2(\partial_x^2 + \partial_y^2 + \partial_z^2) - \partial_t^2 u = 0$$

Wave Field =  $u(x, y, z)$

Wave Speed =  $c$

## Exact dispersion:

$$\omega^2 = c^2(k^2 \cos^2 \theta \cos^2 \phi + k^2 \cos^2 \theta \sin^2 \phi + k^2 \sin^2 \theta)$$

$\omega$  = frequency

$k$  = wavelength

$\phi$  = azimuth angle

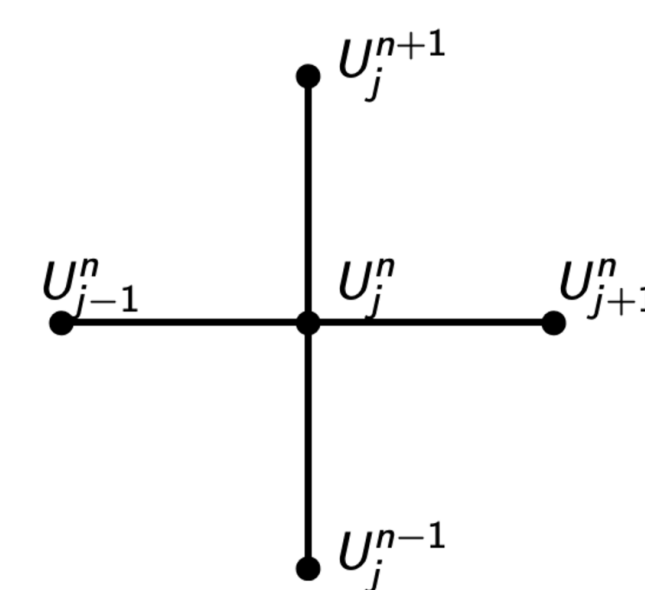
$\theta$  = plane wave propagation

## Methods:

### Finite Difference Schemes:

Finite Difference Schemes use derivatives and a nearby point to approximate a value.

We utilize a finite difference operator where we can change the number of points ( $M$ ) used. Generally, higher  $M$  is more accurate.



### Interpolation:

Interpolation is achieved by replacing the last few accuracy conditions by exact dispersion.

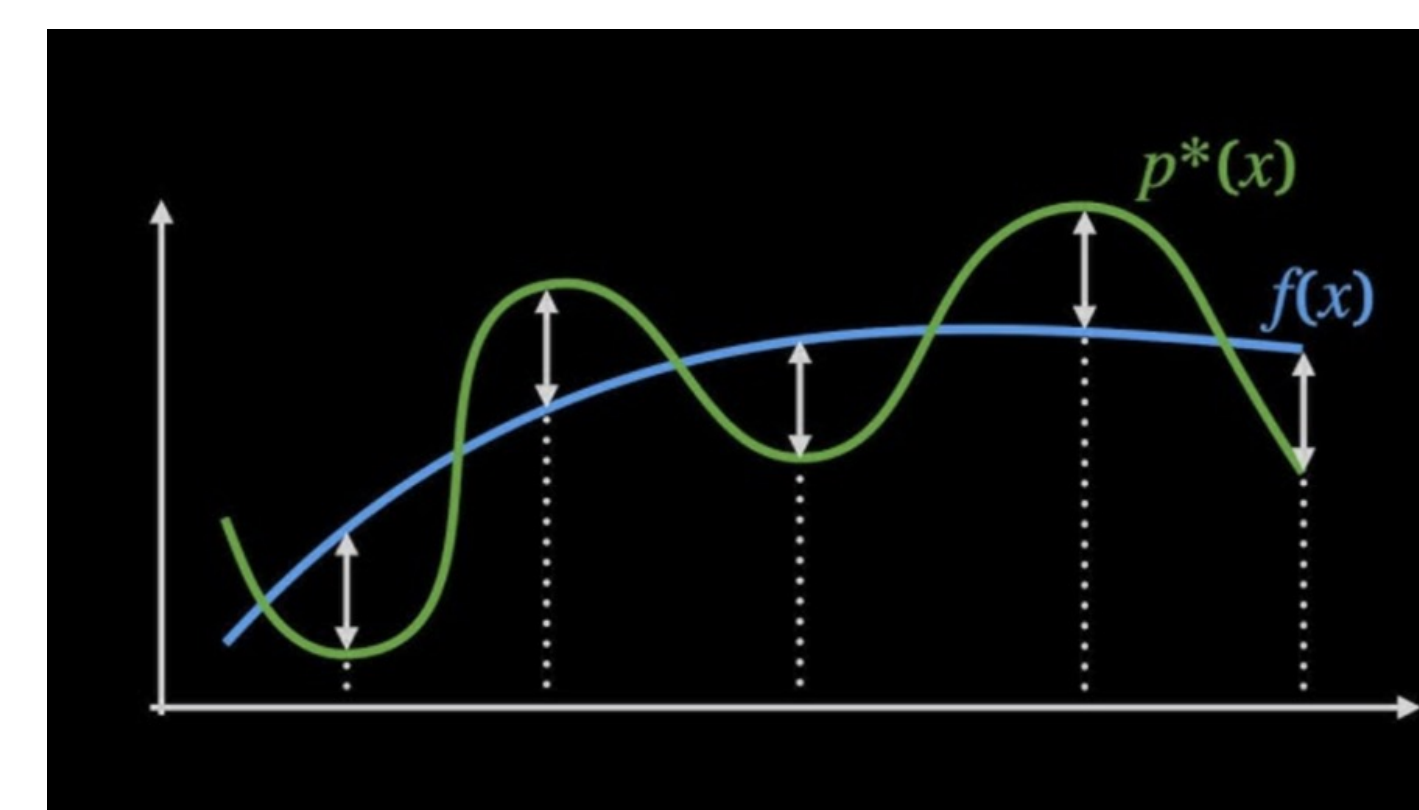
$$\begin{bmatrix} f_{1,1,\theta,\phi} & f_{1,2,\theta,\phi} & \dots & f_{1,j,\theta,\phi} & \dots & f_{1,M,\theta,\phi} \\ f_{2,1,\theta,\phi} & f_{2,2,\theta,\phi} & \dots & f_{2,j,\theta,\phi} & \dots & f_{2,M,\theta,\phi} \\ \vdots & \vdots & \vdots & \vdots & \vdots & \vdots \\ f_{i,1,\theta,\phi} & f_{i,2,\theta,\phi} & \dots & f_{i,j,\theta,\phi} & \dots & f_{i,M,\theta,\phi} \\ \vdots & \vdots & \vdots & \vdots & \vdots & \vdots \\ f_{M,1,\theta,\phi} & f_{M,2,\theta,\phi} & \dots & f_{M,j,\theta,\phi} & \dots & f_{M,M,\theta,\phi} \end{bmatrix} \begin{bmatrix} c_1 \\ c_2 \\ \vdots \\ c_j \\ \vdots \\ c_M \end{bmatrix} = \begin{bmatrix} -(\gamma)^2 \\ -(\gamma)^4 \\ \vdots \\ -(\gamma)^{2j} \\ \vdots \\ -(\gamma)^{2M} \end{bmatrix}$$

$$\begin{bmatrix} f_{1,1,\theta,\phi} & f_{1,2,\theta,\phi} & \dots & f_{1,j,\theta,\phi} & \dots & f_{1,M,\theta,\phi} \\ f_{2,1,\theta,\phi} & f_{2,2,\theta,\phi} & \dots & f_{2,j,\theta,\phi} & \dots & f_{2,M,\theta,\phi} \\ \vdots & \vdots & \vdots & \vdots & \vdots & \vdots \\ g_{K_j,1,\theta,\phi} & g_{K_j,2,\theta,\phi} & \dots & g_{K_j,j,\theta,\phi} & \dots & g_{K_j,M,\theta,\phi} \\ \vdots & \vdots & \vdots & \vdots & \vdots & \vdots \\ g_{K_M,1,\theta,\phi} & g_{K_M,2,\theta,\phi} & \dots & g_{K_M,j,\theta,\phi} & \dots & g_{K_M,M,\theta,\phi} \end{bmatrix} \begin{bmatrix} c_1 \\ c_2 \\ \vdots \\ c_j \\ \vdots \\ c_M \end{bmatrix} = \begin{bmatrix} -(\gamma)^2 \\ -(\gamma)^4 \\ \vdots \\ -\cos(K_j) \\ \vdots \\ -\cos(K_M) \end{bmatrix}$$

## The Remez (Exchange) Algorithm:

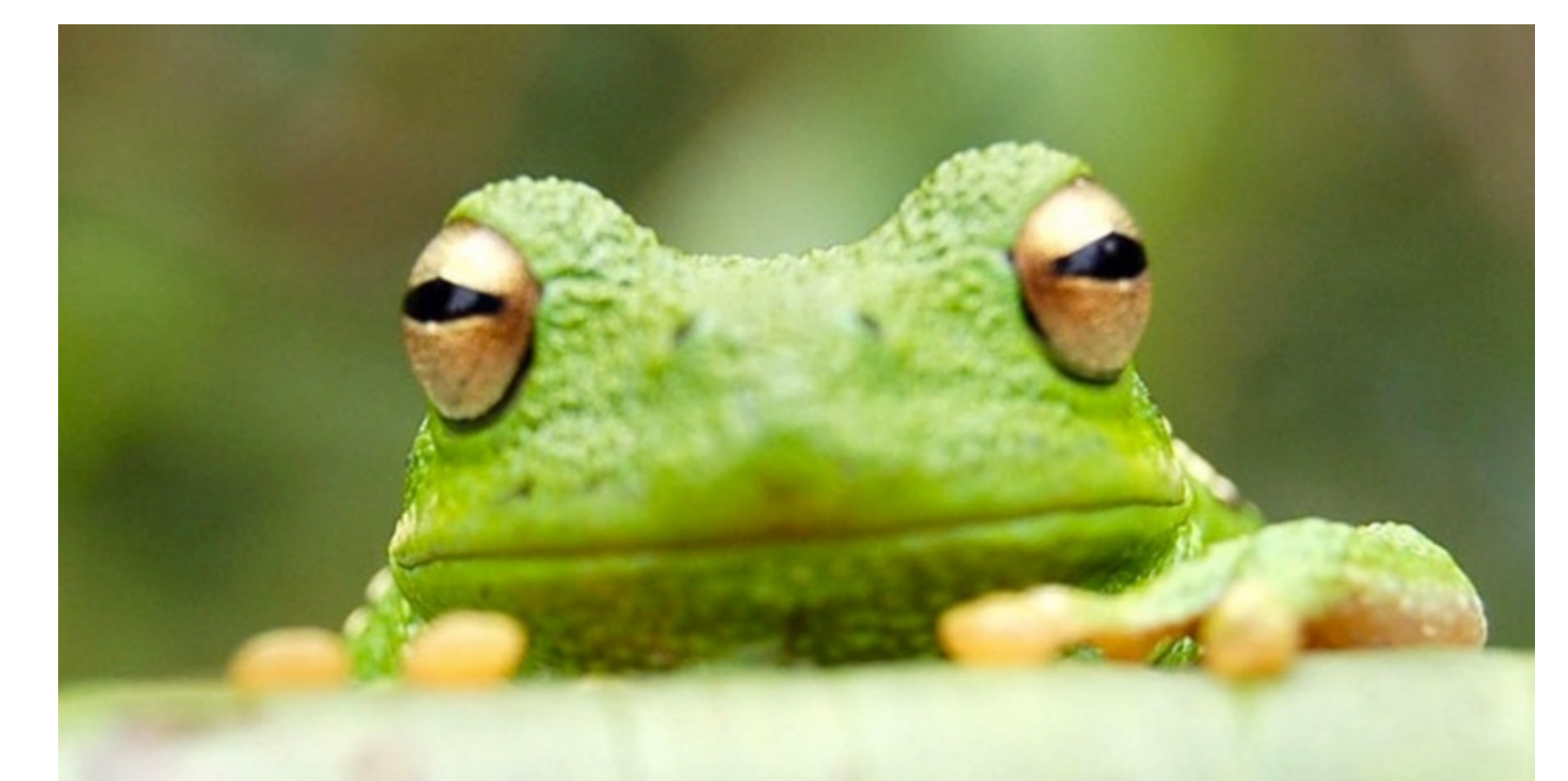
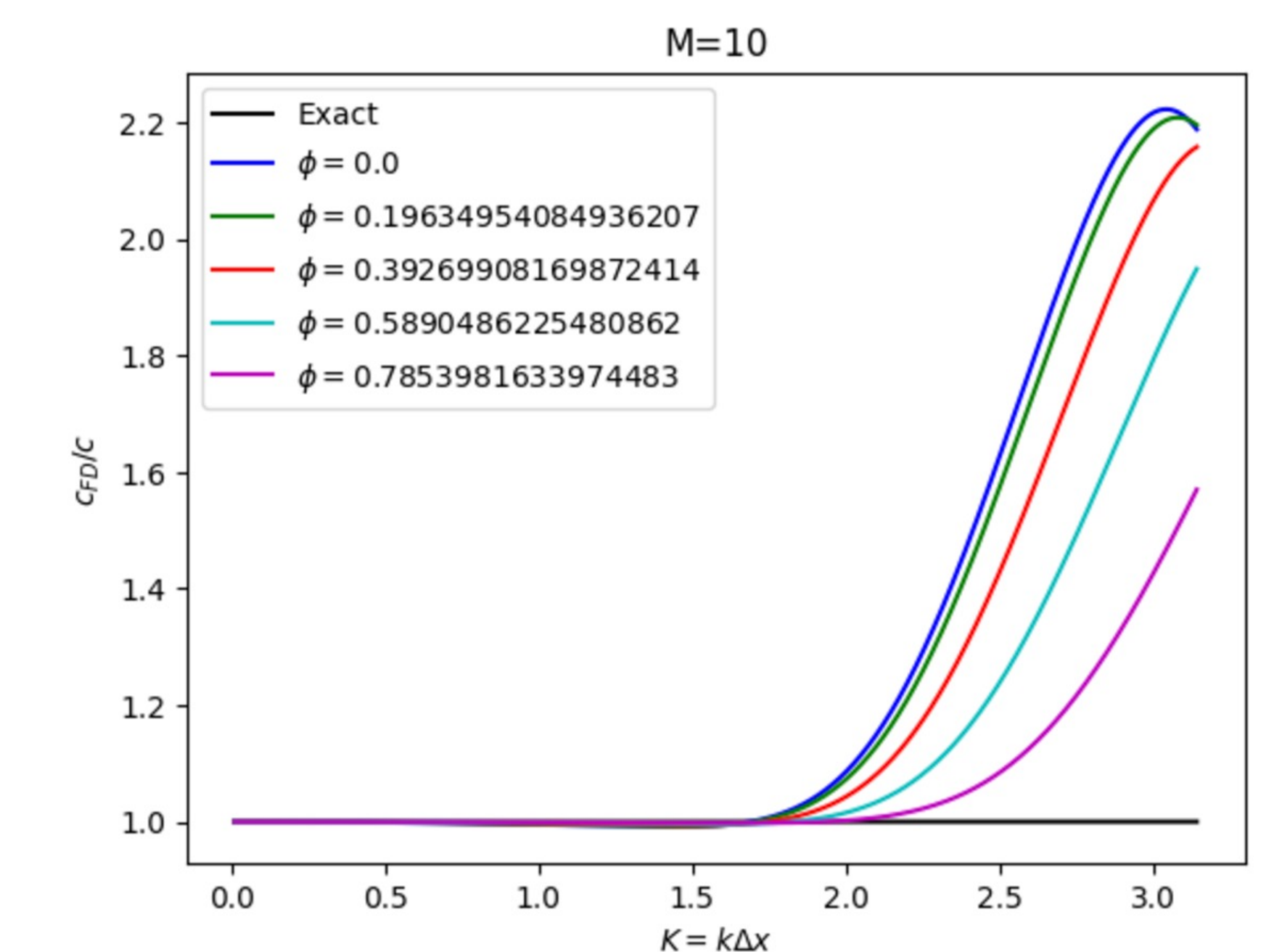
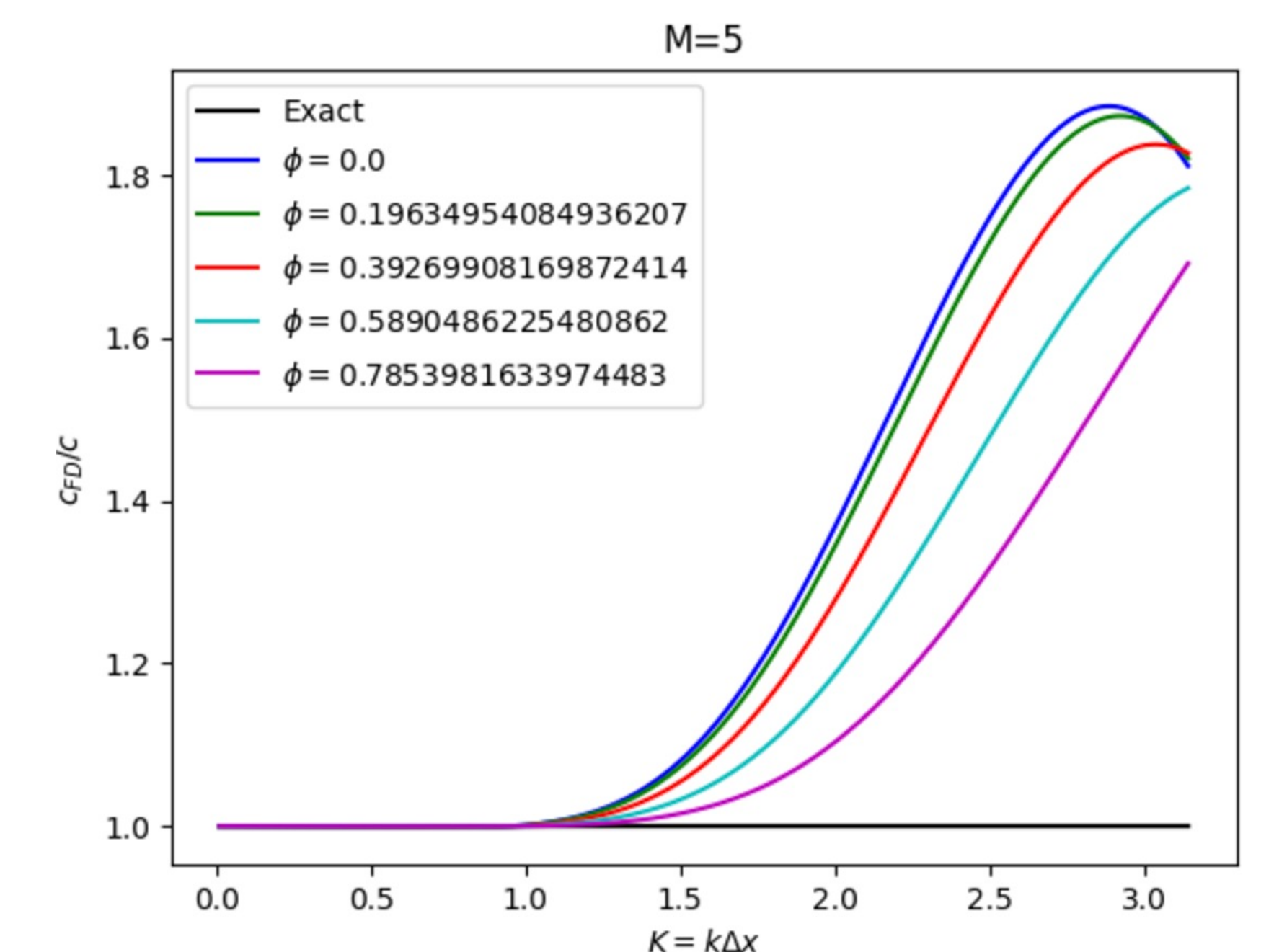
To guarantee accurate dispersion for all wavenumbers/ propagation angles of  $g$ , we utilize the Remez Exchange Algorithm, which utilizes minimax approximation.

Minimax approximation can be used for functions in a Haar space. It takes the difference between the maxima and shifts the function  $f(x)$  to the optimal position that minimizes error.



- Pick a set of reference points  $\{K_i\}_{i=1}^{M+1-l} \in (0, \pi]$ . Denote  $h = f(K_1) - p(K_1, \phi_{preset})$ ,  $h$  is currently unknown and will be solved next step.
- Find the first polynomial  $p(K, \phi_{preset}) = \sum_{m=0}^M c_m [\cos(mK \cos(\phi_{preset})) + \cos(mK \sin(\phi_{preset}))]$  and  $h$  by solving  $p(0, \phi_0) = 1, \quad j = 0$   
 $p^{(2j)}(0, \phi_0) = (-1)^j \gamma^{2j}, \quad j = 1, \dots, l$   
 $p(K_i, \phi_{preset}) + (-1)^{i-1} h = f(K_i, \phi_{preset}), \quad i = 1, \dots, M + 1 - l.$
- Compute the error function  $e(K) = f(K) - p(K, \phi_{preset})$ . Find  $\eta$ , a point where  $|f(\eta) - p(\eta, \phi_{preset})| = \|f - p\|$ , and denote  $\delta = |f(\eta) - p(\eta, \phi_{preset})| - |h|$ .
  - If the difference  $\delta$  is within the preset accuracy, stop and take  $p$  to be the best approximation.
  - If not, replace a point from  $\{K_i\}_{i=1}^{M+1-l}$  with  $\eta$ , denote the new set of reference points by  $\{K_i^+\}_{i=1}^{M+1-l}$ . Let  $h = f(K_1^+) - p(K_1^+, \phi_{preset})$ .
- Repeat above until the difference is below the preset error bound.

## Results



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