Time Integration

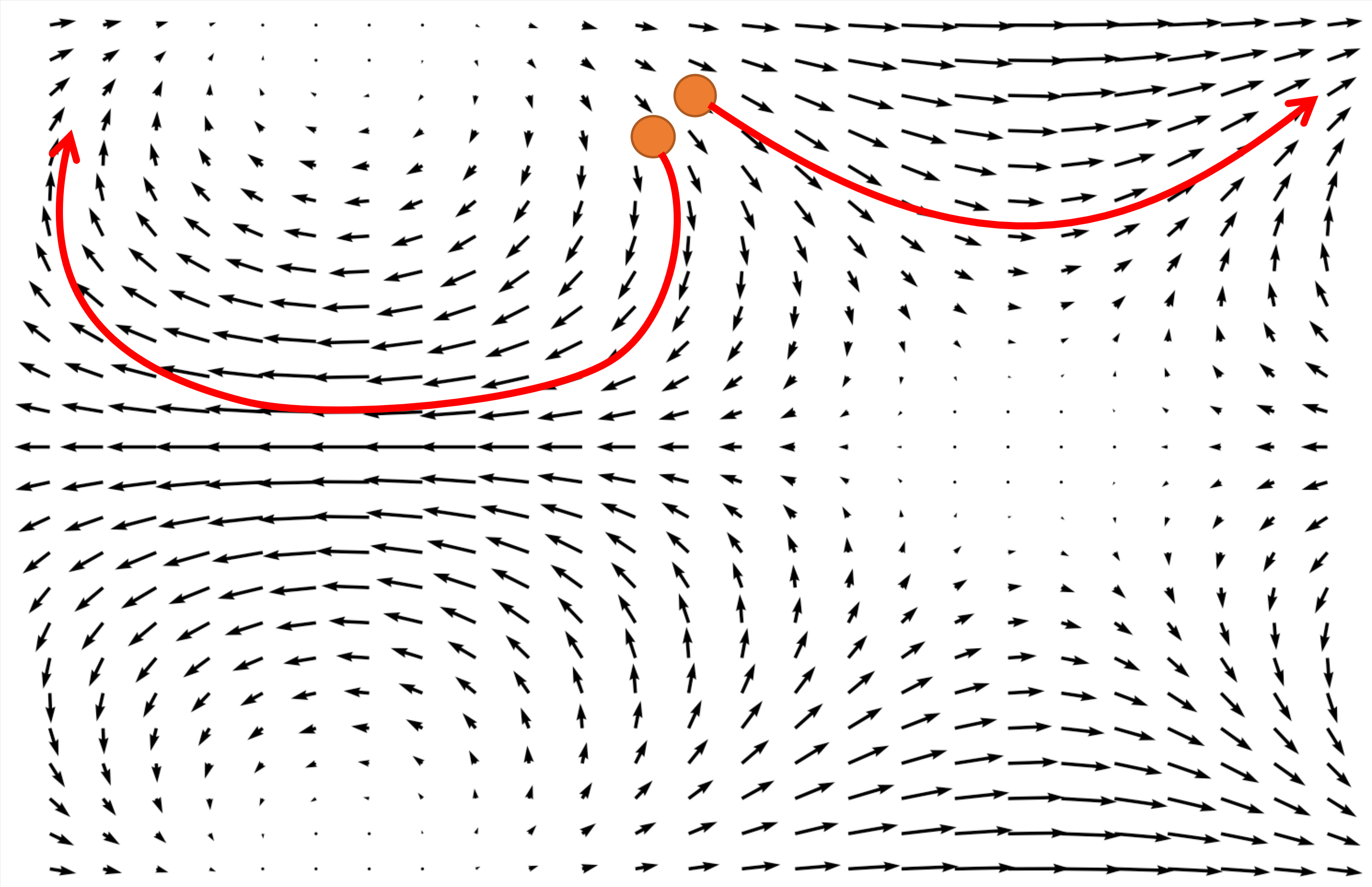
時間積分

System of Differential Equations

連立線形微分方程式

Tracing a Particle in a Velocity Field

- E.g., massless particle in a steady flow



System of 1st Order Differential Equations

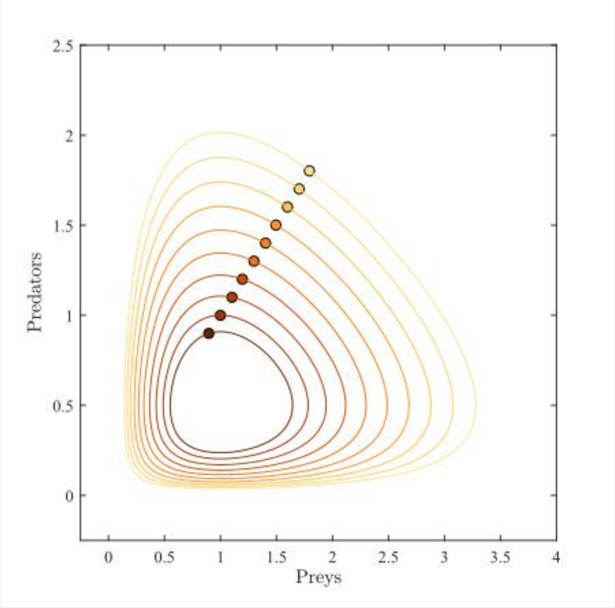
- Moving a particle inside a vector field
  - Electrical engineering
  - Control theory
  - System biology

$$\frac{d\vec{x}}{dt} = f(\vec{x})$$

Lotka–Volterra equations

(a.k.a predetors/preys equation)

$$\frac{dx}{dt} = \alpha x - \beta xy$$
$$\frac{dy}{dt} = \delta xy - \gamma y$$



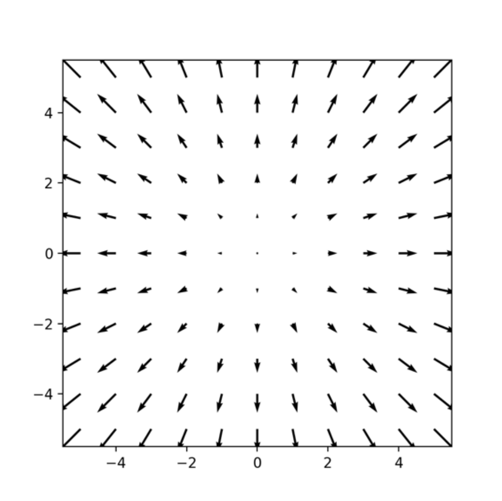
(Wikipedia: Lotka–Volterra equations

Linear 1st Oder System of Diff. Eqn.

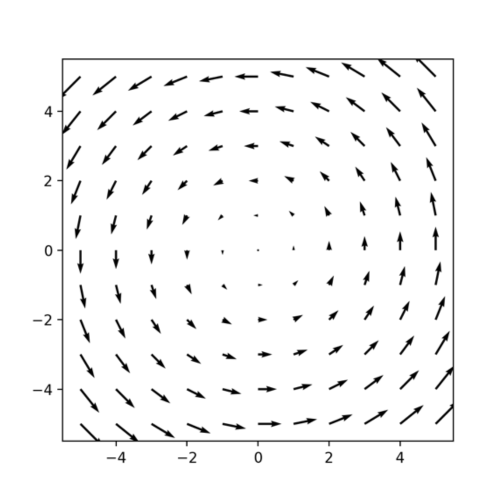
- What if $f(\vec{x})$ is linear?

$$\frac{d\vec{x}}{dt} = A\vec{x}$$

$$A = \begin{bmatrix} 1 & 0 \\ 0 & 1 \end{bmatrix}$$



$$A = \begin{bmatrix} 0 & -1 \\ 1 & 0 \end{bmatrix}$$



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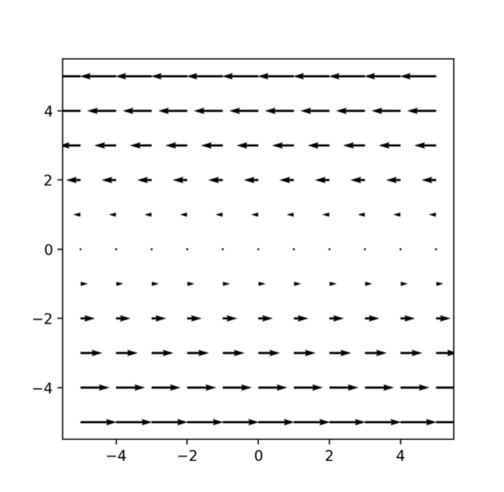


Solution of Differential Equations

1st order differential equation

$$\frac{dx}{dt} = ax \quad \xrightarrow{\text{solution}} \quad x(t) = e^{at}x(0)$$

System of 1st order differential equations

$$\frac{d\vec{x}}{dt} = A\vec{x} \quad \xrightarrow{\text{solution}} \quad \vec{x}(t) = e^{At}\vec{x}(0)$$

Matrix Exponential

- The Taylor expansion of the exponential function

$$e^x = 1 + \frac{1}{1!}x + \frac{1}{2!}x^2 + \frac{1}{3!}x^3 + \cdots$$

$$e^{At} = E + \frac{1}{1!}At + \frac{1}{2!}(At)^2 + \frac{1}{3!}(At)^3 + \cdots$$

$$\frac{d}{dt}(e^{At}) = ?$$

check it out!

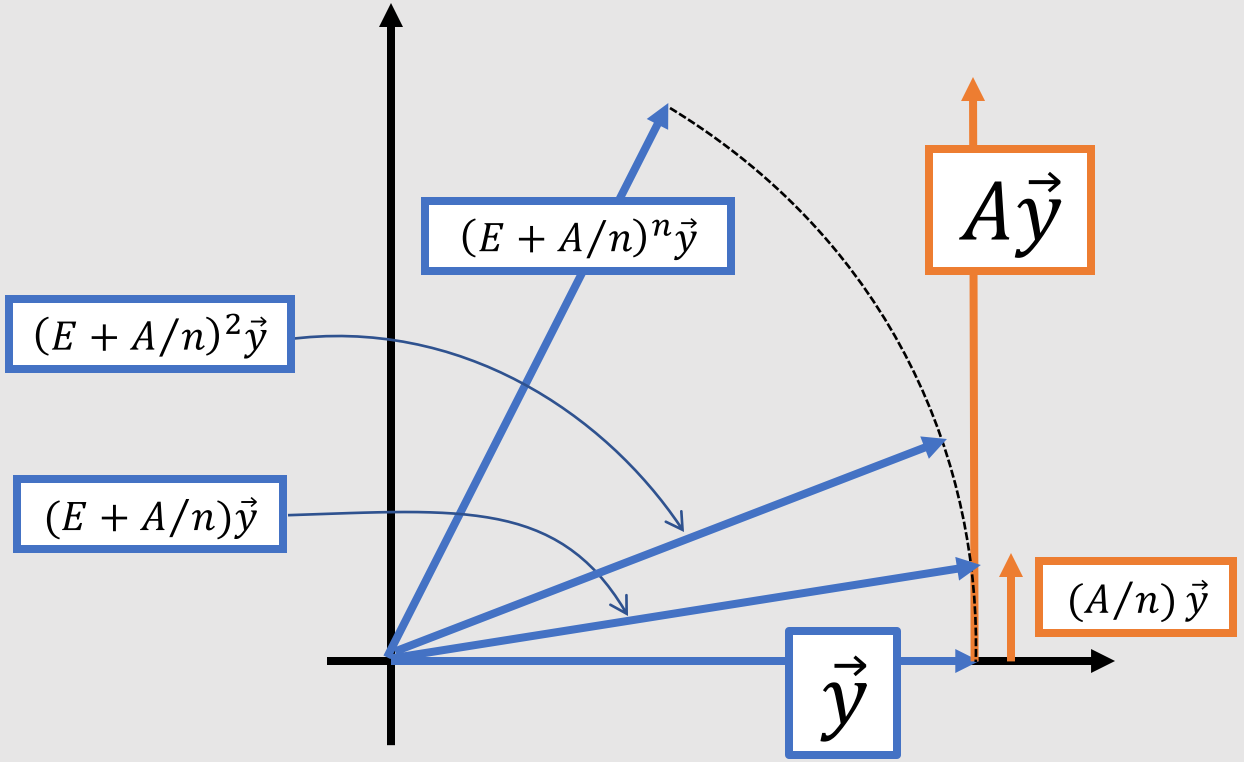
Geometrical Interpretation

- Let's go back to the definition of the exponential

$$e^x = \lim_{n\to\infty}\left(1+\frac{x}{n}\right)^n \quad \xrightarrow{\text{multi-variable}} \quad e^A = \lim_{n\to\infty}\left(E+\frac{A}{n}\right)^n$$

For example, let A is a matrix to compute tangent in 2D

$$A = \begin{bmatrix} 0 & -1 \\ 1 & 0 \end{bmatrix}$$



Compound Interest(複利効果)

$$e = \lim_{n\to\infty}\left(1+\frac{1}{n}\right)^{n}$$

$1 → 100% (12months) → $2

$1 → 50% (6 months) → $1.5 → 50% (6 months) → $2.25

$1 → 25% (3 months) → $1.25 → 25% (3 months) → $1.5625 → 25% (3 months) → $1.95 → 25% (3 months) → $2.4375

$1 → 1/365% (1day) → $..... → 1/365% (1day) → $..... → → $2.714..

$1 → $..... → $..... → $..... → → → $e(2.718..)

Wealth is Exponential

Compound interest is the 8th wonder of the world. He who understands it, earns it; he who doesn't, pays it.

-Albert Einstein

$r>g$

(i.e, you can earn more from investment than working hard)

Thomas Piketty, Capital in the Twenty-First Century

(Wikipedia)

Diagonalization and Matrix Exponential

eigen decomposition

$$Av_i = \lambda_i v_i \quad \Rightarrow \quad A = V\Lambda V^{-1}$$

$$e^{At} = E + \frac{1}{1!}At + \frac{1}{2!}(At)^2 + \frac{1}{3!}(At)^3 + \cdots$$

check it out!

System of 2nd Order Differential Equation

- 2nd order system can be transformed into a 1st order system

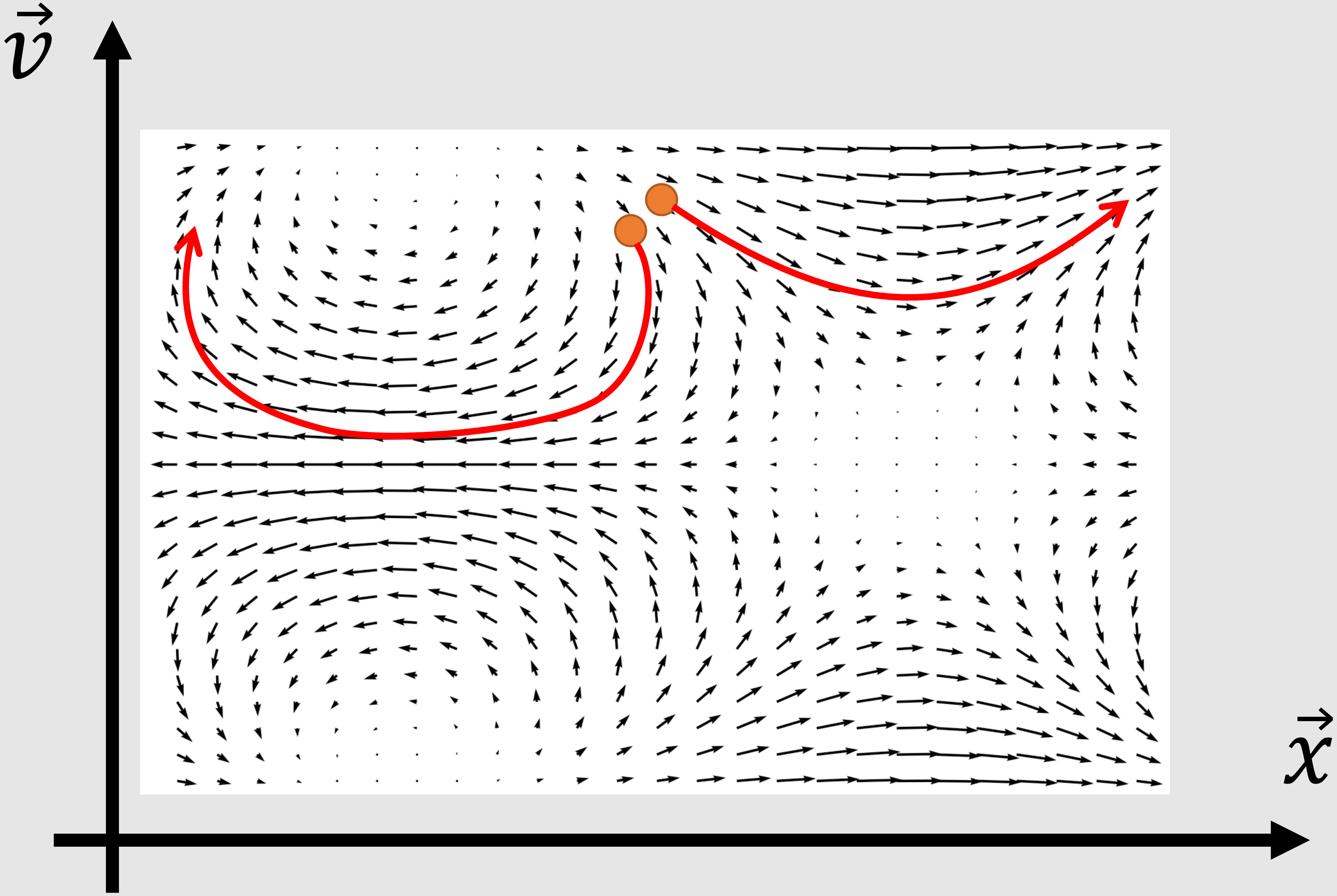
$$\frac{d^2\vec{x}}{dt^2} - A\frac{d\vec{x}}{dt} - \mathrm{B}\vec{x} = 0$$

$$\vec{v} = \frac{d\vec{x}}{dt}$$

$$\frac{d}{dt}\begin{pmatrix}\vec{v}\\ \vec{x}\end{pmatrix} = \begin{bmatrix}A & B\\ E & 0\end{bmatrix}\begin{pmatrix}\vec{v}\\ \vec{x}\end{pmatrix}$$

Analyzing stability of this system requires Laplace transformation, which is beyond the scope of this lecture

Mechanics: Trajectory in **Phase Space**

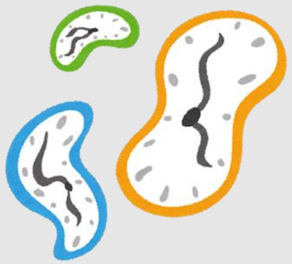


Discrete Time Integration

Why Temporal Discretization?

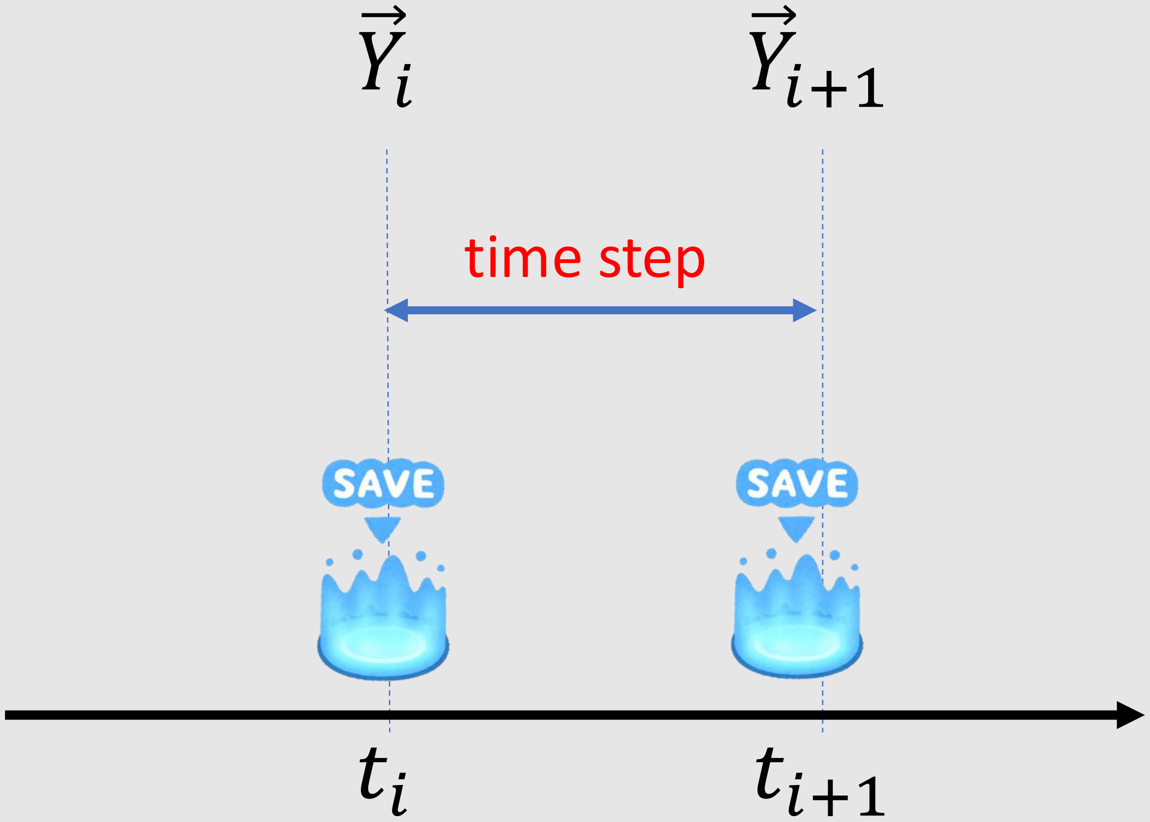
- Dynamic system doesn’t always have an analytical solution

- Computer cannot handle continuous value
  - Similar to “quantization” and “sampling” in audio processing



Time Integration for Temporal Discretization

- The interval is called "time step"



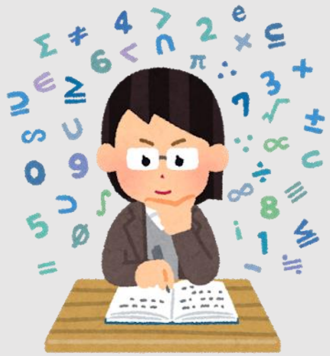
Recurrent formula

$$\vec{Y}_{i+1} = F(\vec{Y}_i)$$

Given equation of motion,
what are the $\vec{Y}_i$ and $F(\ )$?

Approximating Gradient by Difference

$$\frac{dx}{dt} = F(x)$$



forward(explicit)
Euler method

$$\frac{x_{i+1} - x_i}{dt} = F(x_i)$$

Simple but
Unstable

backward(implicit)
Euler method

$$\frac{x_{i+1} - x_i}{dt} = F(x_{i+1})$$

Complicated but
Stable

Recurrence Relation from Backward Euler

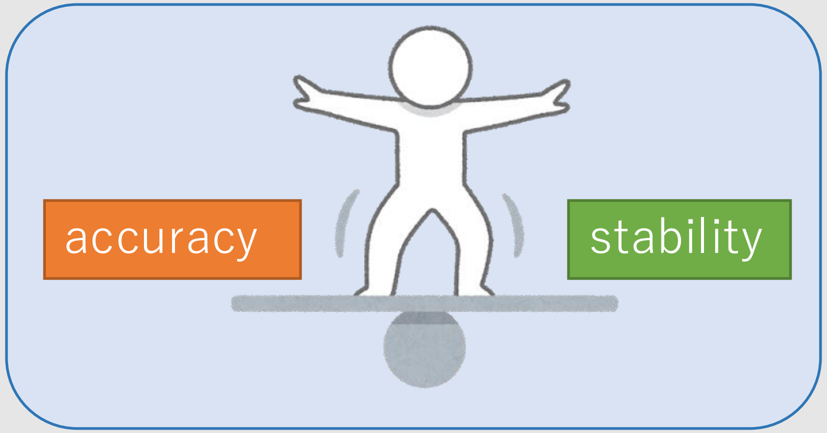
$$\frac{x_{i+1} - x_i}{dt} = F(x_{i+1})$$

Taylor's expansion

$$\cong f(x_i) + \left.\frac{dF}{dx}\right|_{x_i} (x_{i+1} - x_i)$$

(write equation Here)

Accuracy of Time Integration



Forward(explicit) Euler method

$$\frac{x_{i+1} - x_i}{dt} = F(x_i)$$

1st order

Average

Crank-Nicolson method

$$\frac{x_{i+1} - x_i}{dt} = \frac{F(x_i) + F(x_{i+1})}{2}$$

2nd order

Backward (implicit) Euler method

$$\frac{x_{i+1} - x_i}{dt} = F(x_{i+1})$$

1st order

2^{nd}-order Differential Eqn. by Backward Euler

Backward
Euler method

$$\frac{ds}{dt} = \frac{s_{i+1} - s_i}{dt} = F(s_{i+1})$$

plug in $s_i = \begin{pmatrix} \vec{v}_\mathrm{i} \\ \vec{x}_\mathrm{i} \end{pmatrix}$

(write equations here)

Simple Example: Particle Under Gravity

$$m\vec{a} = m\vec{g}$$

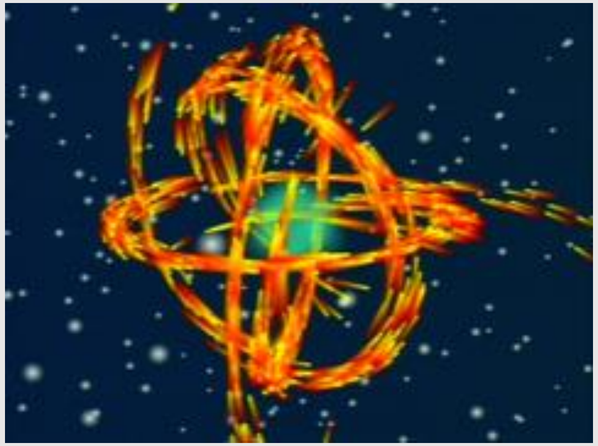
$$\begin{cases} \vec{v}_{i+1} - \vec{v}_i = dt \cdot \vec{a}_{i+1} \\ \vec{x}_{i+1} - \vec{x}_i = dt \cdot \vec{v}_{i+1} \end{cases}$$

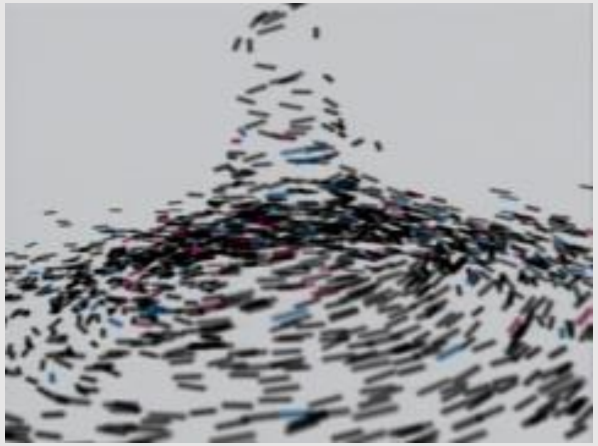
$$\vec{a} = \vec{g}$$

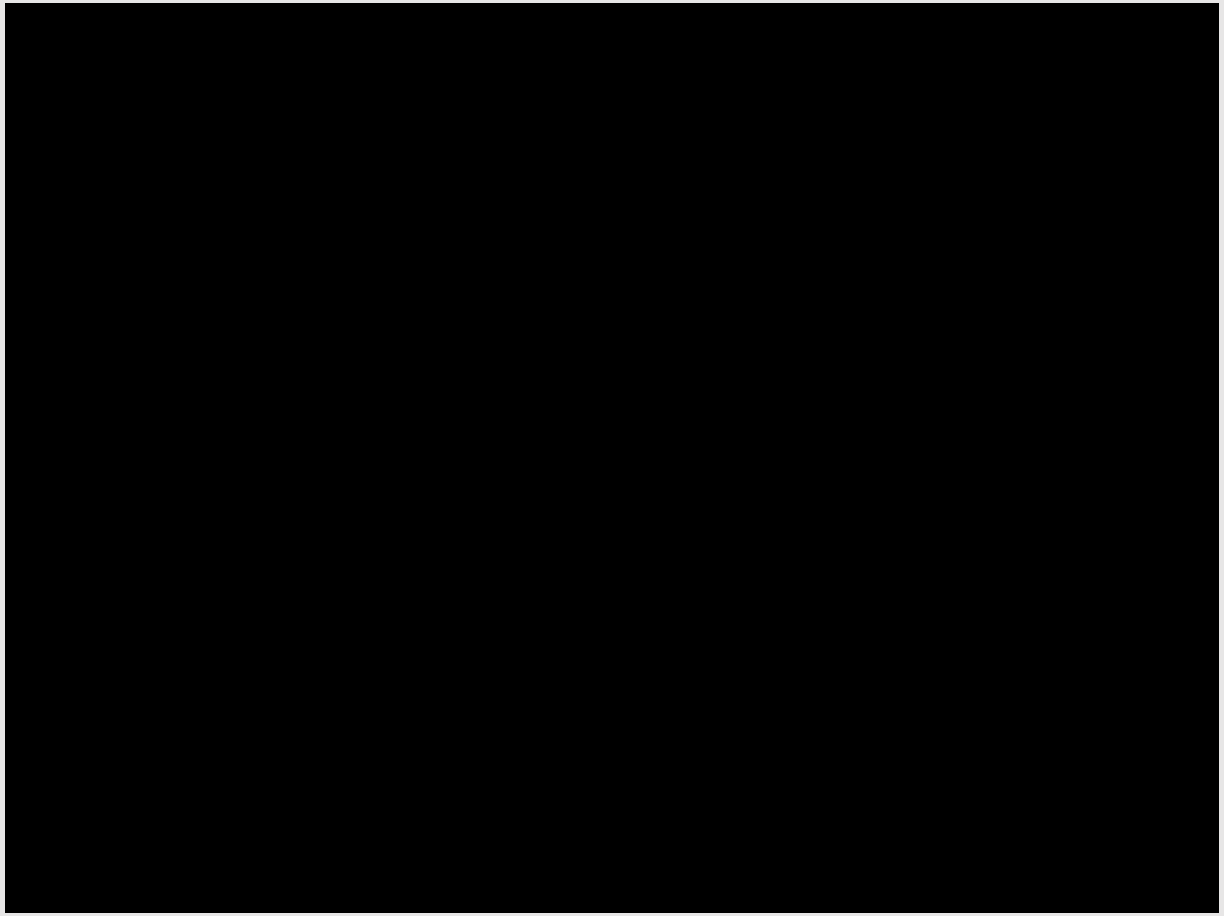
$$\vec{v}_{i+1} = \vec{v}_i + dt \cdot \vec{g}$$
$$\vec{x}_{i+1} = \vec{x}_i + dt \cdot (\vec{v}_i + dt \cdot \vec{g})$$

Karl Sim’s Particle Dreams, 1988

https://www.karlsims.com/particle-dreams.html







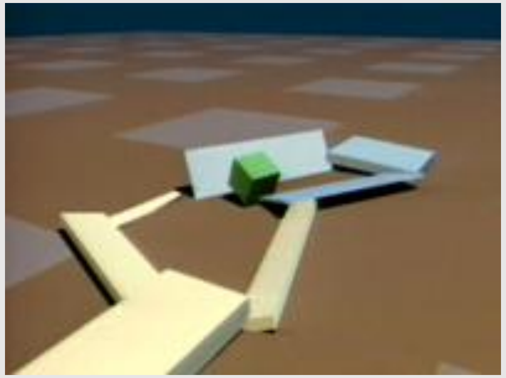
https://www.youtube.com/watch?v=5QEp-oPaQto

Karl Sim’s Another Awesome Work

K.Sims, “Evolved Virtual Creatures ”, Siggraph ‘94

https://www.karlsims.com/evolved-virtual-creatures.html



https://www.youtube.com/watch?v=RZtZia4ZkX8

Advanced Topics

- Runge-Kutta method
- Variational Implicit Euler Method
- Symplectic Integrator
- Lie group integrator

End

Time Integration

Recurrence formula from equation of motion

Position $\vec{x}$ ← Integration ← Velocity $\vec{v}$ ← Integration ← Acceleration $\vec{a}$ ← Eqn. of motion

$$\vec{a} = \frac{1}{m}\vec{F}$$

Time Integration: 1st-order Differential Eqn.

- Given $\vec{x}_i$, solve for $\vec{x}_{i+1}$

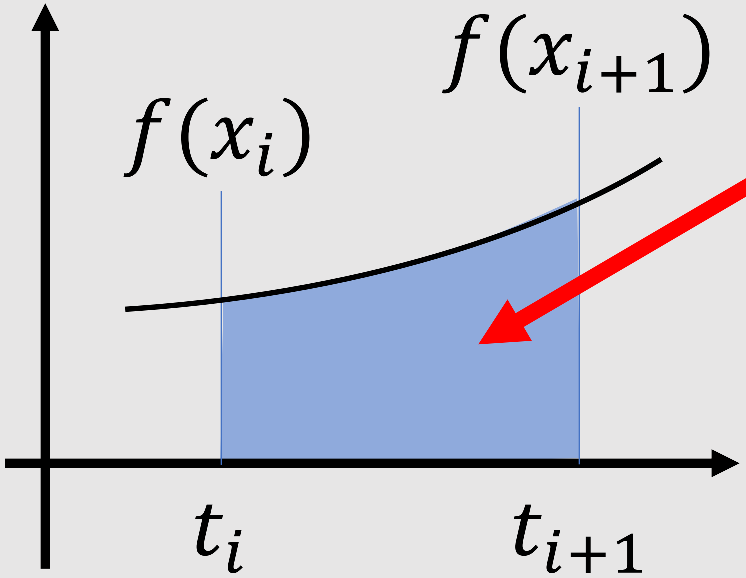
$$\frac{dx}{dt} = f(x) \quad \xrightarrow{\text{Integration}} \quad x_{i+1} = x_i + \int_{t_i}^{t_{i+1}} f(x)\,dt$$

（ここに手書きで式を書く）

Time Integration: 1st-order Differential Eqn.

- Compute $\vec{x}_{i+1}$ when $\vec{x}_i$ is given

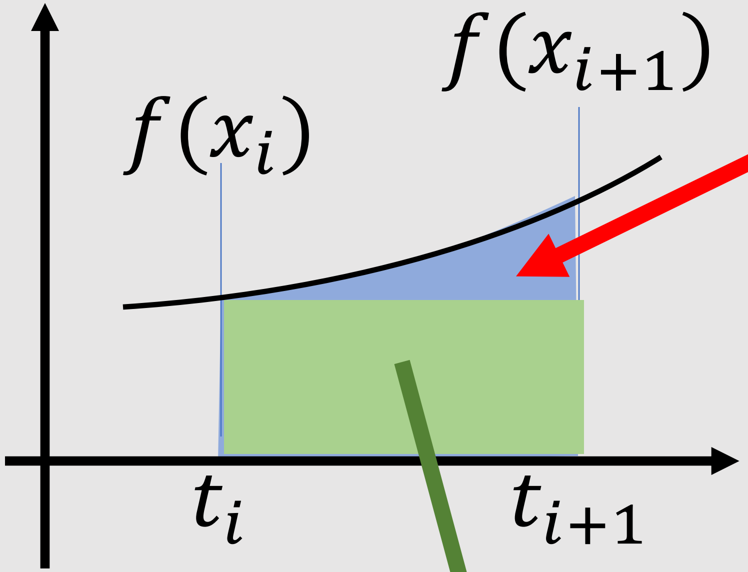
$$\frac{dx}{dt} = f(x) \quad \xrightarrow{\text{integration}} \quad x_{i+1} = x_i + \int_{t_i}^{t_{i+1}} f(x)\,dt$$



Area here makes
$x_{i+1} - x_i$

$f(x)$ is unknown and x is unknown
How the area is approximated

Time Integration: 1st-order Differential Eqn.



Area here makes
$x_{i+1} - x_i$

$f(x)$ is unknown because x is unknown.
How area can be approximated

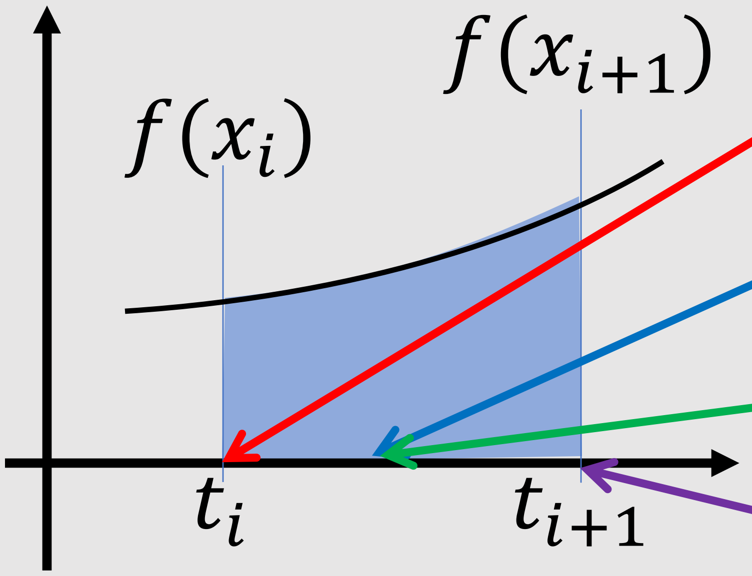
Advanced approach
Runge-Kutta method

Area：$dt \times f(x_i)$

Forward(explicit)
Euler method $x_{i+1} = x_i + dt \times f(x_i)$

Runge-Kutta Method (4th order)

- Approximating are $a = x_{i+1}$- x_i with 4 different ways



$$
\begin{cases}
a_1 = dt \times f(x_i) \\
a_2 = dt \times f(x_i + a_1/2) \\
a_3 = dt \times f(x_i + a_2/2) \\
a_4 = dt \times f(x_i + a_3)
\end{cases}
$$

averaging

$$x_{i+1} = x_i + \frac{1}{6}(a_1 + 2a_1 + 2a_1 + a_1)$$