Preconditioning of sequences of large, sparse and nonsymmetric linear systems

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Outline

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1. Introduction to preconditioner updates

Consider a sequence of linear systems

$$\mathbf{A}^{(i)}x = b^{(i)}, \; i = 1, \ldots, \tag{1}$$

where $\mathbf{A}^{(i)} \in \mathbb{R}^{n\times n}$ are nonsingular sparse matrices; $b^{(i)} \in \mathbb{R}^n$.

Applications: Computational fluid dynamics, structural mechanics, numerical optimization, non-PDE problems.

Classical example: A system of nonlinear equations $F(x) = 0$ for $F : \mathbb{R}^n \to \mathbb{R}^n$ solved by a Newton or Broyden-type method leading to

$$\mathbf{J}(x_i)(x_{i+1} - x_i) = -F(x_i), \; i = 1, \ldots,$$

where $\mathbf{J}(x_i)$ is the Jacobian evaluated in the current iteration x_i or its approximation.

There is a strong need for reduction of costs by sharing some of the computational effort among the subsequent linear systems.

Some options to reduce overall costs:

- Modify Newton's method by skipping some Jacobian evaluations: Shamanskii combination of Newton's method and the Newton-chord method. Much weaker nonlinear convergence properties than the standard Newton's method.
- The sequence of linear systems must often be preconditioned; computing preconditioners $\mathbf{M}^{(1)}, \mathbf{M}^{(2)}, \ldots$ for individual systems separately, may be very expensive. A remedy is freezing the preconditioner: Using the same preconditioner for a sequence of linear systems (see, e.g [Brown, Saad - 1990]).

This approach is very natural in the context of a matrix-free environment, where the system matrices $\mathbf{A}^{(i)}$ may be available only in the form of matrix-vector products, see also [Knoll, Keyes - 2004].

Freezing the preconditioner need not be enough. We may reuse some *additional* information from the linear system $A^{(1)}x = b^{(1)}$. For example:

- In the Newton-Krylov framework: Recycle Krylov subspaces among systems of a sequence, see e.g. [Loghin, Ruiz, Touhami-2004], [Parks, de Sturler, Mackey, Johnson, Maiti - 2004].
- Many interesting algorithms were proposed for exact updates of decompositions. Recent sparse updates [Davis, Hager - 1999, 2001, 2005] replace in some cases classical dense updates from, e.g., [Gill, Murray, Saunders - 1975].

- There is some recent work in approximate updates as well. Approximate diagonal updates of approximate inverse preconditioners for solving parabolic PDEs were proposed in [Benzi, Bertaccini - 2003], see also [Bertaccini - 2004]. A straightforward approximate rank one update for a quasi-Newton method in the SPD case is described in [Morales, Nocedal - 2000], [Bergamaschi, Bru, Martinez, Putti - 2001].

We present new approaches to approximate updates of factorized, and general nonsymmetric preconditioners which may be useful in solving subsequent linear systems. We do not confine ourselves to particular classes of linear solvers (e.g. Krylov subspace methods).

We address the following 2 problems:

- How can we update, in theory, a preconditioner in such a way that the updated preconditioner is likely to be as powerful as the original one?

- How can we approximate, in practice, such an update in order to obtain a preconditioner that is inexpensive to compute and to apply?

Consider two linear systems denoted by

$$\mathbf{A}x = b \qquad \text{and} \qquad \mathbf{A}^{+}x^{+} = b^{+}.$$

Denote the difference matrix $\mathbf{A} - \mathbf{A}^{+}$ by $\mathbf{B}$.
Let $\mathbf{M}$ be a preconditioner approximating $\mathbf{A}$.
The quality of the preconditioner $\mathbf{M}$ can be expressed by

$$\mathbf{A} - \mathbf{M} \tag{2}$$

in some norm or by a norm of one of the matrices

$$\mathbf{I} - \mathbf{M}^{-1}\mathbf{A} \quad \text{or} \quad \mathbf{I} - \mathbf{A}\mathbf{M}^{-1} \tag{3}$$

if we consider preconditioning from the left or right, respectively (see, e.g. [Benzi, Bertaccini - 2003]). While the norm of the matrix (2) expresses *accuracy* of the preconditioner, the norms of the matrices (3) relate to its *stability* [Chow, Saad - 1997], see also [Benzi, Haws, Tůma - 2000].

We have

$$\|\mathbf{A} - \mathbf{M}\| = \|\mathbf{A} - \mathbf{M} + \mathbf{A}^{+} - \mathbf{A}^{+}\| = \|\mathbf{A}^{+} - (\mathbf{M} - \mathbf{B})\|,$$

hence $\mathbf{M}^{+} \equiv \mathbf{M} - \mathbf{B}$ is an updated preconditioner for $\mathbf{A}^{+}$ of the same "level" of accuracy as $\mathbf{M}$ is for $\mathbf{A}$.

This "ideal" updated preconditioner cannot be used, in general, in practice since multiplication of vectors with $(\mathbf{M} - \mathbf{B})^{-1}$ may be too expensive.

There are ways, however, to approximate multiplication with $(\mathbf{M} - \mathbf{B})^{-1}$, as we will now show.

2. Proposed sparse preconditioner updates

Assume $\mathbf{M} = \mathbf{LDU} \approx \mathbf{A}$, where $\mathbf{L}$ and $\mathbf{U}$ are lower, resp. upper triangular and have unit main diagonal.

The derivation of some of our updates is based on the assumption that the entries of $\mathbf{L}$ and $\mathbf{U}$ decay when moving away from the main diagonal, see e.g. [Benzi, Tůma - 2000], [Benzi, Bertaccini - 2003]. Sufficient diagonal dominance may also be imposed if $\mathbf{A}$ contains a strong transversal [Olschowka, Neumaier - 1996], [Duff, Koster - 1999, 2001] such that its entries can be permuted to the main diagonal. Thus we assume more or less

$$\mathbf{L} \approx \mathbf{I} \approx \mathbf{U}.$$

We can approximate $(\mathbf{M}-\mathbf{B})^{-1}$, if it is nonsingular, as

$$(\mathbf{M}-\mathbf{B})^{-1} = \left(\mathbf{L}(\mathbf{D}-\mathbf{L}^{-1}\mathbf{B}\mathbf{U}^{-1})\mathbf{U}\right)^{-1} \approx \mathbf{U}^{-1}(\mathbf{D}-\mathbf{B})^{-1}\mathbf{L}^{-1},$$

provided $\mathbf{D}-\mathbf{B}$ is nonsingular. Denote by $\overline{\mathbf{D}-\mathbf{B}}$ a nonsingular approximation of $\mathbf{D}-\mathbf{B}$ that can be inverted inexpensively. Then define a preconditioner $\mathbf{M}^{+}$ as

$$\mathbf{M}^{+} = \mathbf{L}(\overline{\mathbf{D}-\mathbf{B}})\mathbf{U}. \tag{4}$$

The accuracy of this preconditioner can be significantly higher than the accuracy of the frozen preconditioner $\mathbf{M} = \mathbf{LDU}$ for $\mathbf{A}^{+}$:

Lemma 1. Let $||\mathbf{A}-\mathbf{LDU}|| = \varepsilon||\mathbf{A}|| < ||\mathbf{B}||$. Then

$$||\mathbf{A}^{+}-\mathbf{M}^{+}|| \leq ||\mathbf{A}^{+}-\mathbf{LDU}|| \frac{||\mathbf{L}(\mathbf{D}-\overline{\mathbf{D}-\mathbf{B}})\mathbf{U}-\mathbf{B}|| + \varepsilon||\mathbf{A}||}{||\mathbf{B}|| - \varepsilon||\mathbf{A}||},$$

with

$$\frac{||\mathbf{L}(\mathbf{D} - \overline{\mathbf{D} - \mathbf{B}})\mathbf{U} - \mathbf{B}|| + \varepsilon||\mathbf{A}||}{||\mathbf{B}|| - \varepsilon||\mathbf{A}||} \leq$$

$$\frac{\|\mathbf{L}\| \, \|\mathbf{D} - \mathbf{B} - \overline{\mathbf{D} - \mathbf{B}}\| \, \|\mathbf{U}\| + ||\mathbf{L} - \mathbf{I}|| \, \|\mathbf{BU}\| + \|\mathbf{B}\| \, ||\mathbf{U} - \mathbf{I}|| + \varepsilon||\mathbf{A}||}{||\mathbf{B}|| - \varepsilon||\mathbf{A}||}.$$

In the symmetric case, the preconditioner $\mathbf{M}^+$ changes to $\mathbf{M}^+ = \mathbf{L}(\overline{\mathbf{D} - \mathbf{B}})\mathbf{L}^T$, hence symmetry is preserved. In the nonsymmetric case we can assume that only one of the two factors $\mathbf{L}, \mathbf{U}$ is close to the identity matrix, instead of both. We can approximate as

$$(\mathbf{M} - \mathbf{B})^{-1} = \left(\mathbf{L}(\mathbf{DU} - \mathbf{L}^{-1}\mathbf{B})\right)^{-1} \approx (\mathbf{DU} - \mathbf{B})^{-1}\mathbf{L}^{-1},$$

if $\mathbf{DU} - \mathbf{B}$ is nonsingular. If $\overline{\mathbf{DU} - \mathbf{B}}$ denotes a nonsingular and easily invertible approximation of $\mathbf{DU} - \mathbf{B}$, then we define $\mathbf{M}^+$ by

$$\mathbf{M}^{+} = \mathbf{L}(\overline{\mathbf{DU} - \mathbf{B}}). \tag{5}$$

Lemma 2. Let $||\mathbf{A} - \mathbf{LDU}|| = \varepsilon||\mathbf{A}|| < ||\mathbf{B}||$. Then the preconditioner from (5) satisfies

$$||\mathbf{A}^{+} - \mathbf{M}^{+}|| \le ||\mathbf{A}^{+} - \mathbf{LDU}|| \frac{||\mathbf{L}(\mathbf{DU} - \overline{\mathbf{DU} - \mathbf{B}}) - \mathbf{B}|| + \varepsilon||\mathbf{A}||}{||\mathbf{B}|| - \varepsilon||\mathbf{A}||}$$

$$\le ||\mathbf{A}^{+} - \mathbf{LDU}|| \cdot \frac{\|\mathbf{L}\| \, \|\mathbf{DU} - \mathbf{B} - \overline{\mathbf{DU} - \mathbf{B}}\| + ||\mathbf{L} - \mathbf{I}|| \, \|\mathbf{B}\| + \varepsilon||\mathbf{A}||}{||\mathbf{B}|| - \varepsilon||\mathbf{A}||}.$$

Next we propose approximations of $\mathbf{DU} - \mathbf{B}$. All techniques we treat can be analogously formulated for updates of the form $(\overline{\mathbf{LD} - \mathbf{B}})\mathbf{U}$. The introduced algorithms can be used to approximate the matrix $\overline{\mathbf{D} - \mathbf{B}}$ as well.

A very simple choice of $\overline{\mathbf{DU}-\mathbf{B}}$ for $\mathbf{M}^+$ in (5) is

$$\overline{\mathbf{DU}-\mathbf{B}} \equiv triu(\mathbf{DU}-\mathbf{B}), \qquad \mathbf{M}^+ = \mathbf{L}\cdot triu(\mathbf{DU}-\mathbf{B}), \tag{6}$$

where $triu$ denotes the upper triangle (including the main diagonal). From Lemma 2, assuming $\mathbf{L} \approx \mathbf{I}$, $\mathbf{M}^+$ is accurate if the upper triangle of **B** contains an important part of the whole difference matrix **B**. This seems to be the case if the difference matrix is rather nonsymmetric as in upwind/downwind perturbations in nonlinear convection-diffusion problems.

We might consider ways to improve efficiency of the backward solve by sparsification if the factor **U** is rather dense. Denoting by the subindices $[i_1, \ldots, i_l]$ the l upper subdiagonals that start in columns $i_1, \ldots, i_l$ (and the main diagonal by the subindex 0) we considered also choices of the form

$$\overline{\mathbf{DU}-\mathbf{B}} \equiv (\mathbf{DU}-\mathbf{B})_{[i_1,\ldots,i_l]}, \qquad \mathbf{M}^+ = \mathbf{L}\cdot(\mathbf{DU}-\mathbf{B})_{[i_1,\ldots,i_l]}. \tag{7}$$

In particular, if the entries of **B** dominate those of **DU** (in magnitude) we may choose only indices corresponding to upper subdiagonals of **B** (the difference matrix is sparse).

Further simplification eventually leads to

$$\overline{\mathbf{DU} - \mathbf{B}} \equiv \mathrm{diag}(\mathbf{DU} - \mathbf{B}), \qquad \mathbf{M}^{+} = \mathbf{L} \cdot \mathrm{diag}(\mathbf{DU} - \mathbf{B}) \tag{8}$$

which still yields a useful update in some applications and which is a straightforward generalization of the approach from [Benzi, Bertaccini - 2003] for solving a more general problem.

Example: The two-dimensional nonlinear convection-diffusion problem [Kelley - 1995]

$$\Delta u - Ru\nabla u = 2000x(1-x)y(1-y), \; R = 50, \tag{9}$$

on the unit square, discretized by 5-point finite differences on a uniform 70x70 grid with as initial approximation the discretization of $u_0(x, y) = 0$.

$\mathbf{A}/\mathbf{M}$	LDU	$\mathbf{L} \cdot triu(\mathbf{DU} - \mathbf{B})$
$\mathbf{A}^{(1)}$ / $\mathbf{M}^{(1)}$	21	21
$\mathbf{A}^{(2)}$ / $\mathbf{M}^{(1)}$	29	25
$\mathbf{A}^{(3)}$ / $\mathbf{M}^{(1)}$	39	27
$\mathbf{A}^{(4)}$ / $\mathbf{M}^{(1)}$	52	25
$\mathbf{A}^{(5)}$ / $\mathbf{M}^{(1)}$	77	25
$\mathbf{A}^{(6)}$ / $\mathbf{M}^{(1)}$	80	26
$\mathbf{A}^{(7)}$ / $\mathbf{M}^{(1)}$	102	26
$\mathbf{A}^{(8)}$ / $\mathbf{M}^{(1)}$	102	27
$\mathbf{A}^{(9)}$ / $\mathbf{M}^{(1)}$	98	27
$\mathbf{A}^{(10)}$ / $\mathbf{M}^{(1)}$	101	26
$\mathbf{A}^{(11)}$ / $\mathbf{M}^{(1)}$	99	26
$\mathbf{A}^{(1)-(11)}$ / $\mathbf{M}^{(1)-(11)}$	21 ± 5	—

Numbers of BiCGSTAB iterations for solving preconditioned linear systems of a nonlinear convection-diffusion problem with no updates and triangular updates, respectively. $\mathbf{M}^{(1)} = ILUT(0.1, 5)$.

The presented strategies are strongly based on confining the update to the upper (or, equivalently, lower) triangle. Whereas numerical experiments seem to indicate this makes sense, there may be applications where it is necessary to take into account both triangles of the difference matrix.

Here we introduce a strategy to approximate $\mathbf{DU}-\mathbf{B}$ by a general non-triangular but easily invertible matrix. Denote the matrix $\mathrm{diag}\overline{(\mathbf{DU}-\mathbf{B})}$ by $\tilde{\mathbf{D}}$, and $\tilde{\mathbf{D}}^{-1}(\tilde{\mathbf{D}}-\overline{\mathbf{DU}-\mathbf{B}})$ denote by $\tilde{\mathbf{B}}$. Then

$$\overline{\mathbf{DU}-\mathbf{B}} = \tilde{\mathbf{D}}(\mathbf{I}-\tilde{\mathbf{B}}). \tag{10}$$

First consider the case when $\tilde{\mathbf{B}} = \beta e_i e_j^T$, for some $1 \le i, j \le n, i \neq j$. Then we get

$$(\mathbf{I}-\tilde{\mathbf{B}})^{-1} = \mathbf{I} + \frac{\beta}{1-\beta e_j^T e_i} e_i e_j^T = \mathbf{I} + \beta e_i e_j^T, \tag{11}$$

a Gauss-Jordan transformation [Golub, van Loan - 1996] with fill-in free inverse.

Idea: Approximate $\mathbf{DU} - \mathbf{B}$ by a product of Gauss-Jordan transformations.

We achieve this as follows: $\overline{\mathbf{DU} - \mathbf{B}}$ will consist of the main diagonal plus some rows of $\mathbf{DU} - \mathbf{B}$:

$$\begin{aligned} \overline{\mathbf{DU} - \mathbf{B}} &= \tilde{\mathbf{D}}(\mathbf{I} - \tilde{\mathbf{B}}) = \tilde{\mathbf{D}}(\mathbf{I} - \sum_{j=1}^{K} e_{i_j}\tilde{b}_{i_j *}) \\ &= \tilde{\mathbf{D}}(\mathbf{I} - e_{i_1}\tilde{b}_{i_1 *})(\mathbf{I} - e_{i_2}\tilde{b}_{i_2 *})\ldots(\mathbf{I} - e_{i_K}\tilde{b}_{i_K *}), \quad (12) \end{aligned}$$

where $\tilde{b}_{j*} = e_j^T \tilde{\mathbf{B}}$.

If $row(i) = \{k | i \neq k \wedge \tilde{b}_{ik} \neq 0\}$, then the number of operations for multiplying a vector by a matrix of the form (12) or its inverse is at most $2\sum_{j=1}^{K} |row(i_j)| + n$.

Clearly,

$$(\mathbf{I} - e_{i_1}\tilde{b}_{i_1*})(\mathbf{I} - e_{i_2}\tilde{b}_{i_2*}) = (\mathbf{I} - e_{i_1}\tilde{b}_{i_1*} - e_{i_2}\tilde{b}_{i_2*} + e_{i_1}\tilde{b}_{i_1*} \cdot e_{i_2}\tilde{b}_{i_2*})$$
$$= (\mathbf{I} - e_{i_1}\tilde{b}_{i_1*} - e_{i_2}\tilde{b}_{i_2*}) \quad \text{if and only if} \quad e_{i_1}\tilde{b}_{i_1*} \cdot e_{i_2}\tilde{b}_{i_2*} = 0.$$

Theorem 1: Let $\mathbf{I} - \tilde{\mathbf{B}} = \mathbf{I} - \sum_{j_l:l=1,\dots,K} e_{j_l}\tilde{b}_{j_l*}$. Then

$$\mathbf{I} - \tilde{\mathbf{B}} = (\mathbf{I} - e_{i_1}\tilde{b}_{i_1*})(\mathbf{I} - e_{i_2}\tilde{b}_{i_2*}) \dots (\mathbf{I} - e_{i_K}\tilde{b}_{i_K*}) \qquad (13)$$

if and only if

$$i_l \notin \bigcup_{k=1}^{l-1} row(i_k) \text{ for } 2 \le l \le K \qquad (14)$$

for all $i_1, \dots, i_K$ such that $\{j_1, \dots, j_K\} = \{i_1, \dots, i_K\}$.

Example: A unit lower triangular matrix $\mathbf{I} - \tilde{\mathbf{B}}$ can be written as

$$(\mathbf{I} - e_2\tilde{b}_{2*})(\mathbf{I} - e_3\tilde{b}_{3*})(\mathbf{I} - e_4\tilde{b}_{4*}) \dots (\mathbf{I} - e_{n-1}\tilde{b}_{n-1}*)(\mathbf{I} - e_n\tilde{b}_n*).$$

In case of a unit lower triangular matrix $\mathbf{I} - \tilde{\mathbf{B}}$ with k additional subsequent subdiagonals starting in the lth column a product of Gauss-Jordan transformations with a fill-in free inverse can cover only $l/(2l + k - 1)$ percent of the rows.

Changes in a sequence of matrices restricted to a couple of diagonals are rather frequent.

A simple greedy procedure based on sparsification and Theorem 1 is the following algorithm.

Algorithm to find rows i_l of $\mathbf{DU}-\mathbf{B}$ such that it is approximated by a product of Gauss-Jordan transformations.

1. set $\mathcal{R} = \{1,\ldots,n\}$, $l = 0$
2. for $k = 1,\ldots,n$ do
3. set $row(k) = \{i | i \neq k \wedge |(\mathbf{DU}-\mathbf{B})_{ki}| > tol\}$
4. set $p_k = \sum_{j \in row(k)} |(\mathbf{DU}-\mathbf{B})_{kj}|$
5. end for
6. while $\mathcal{R} \neq 0$ do
7. choose a row $i \in \mathcal{R}$ maximizing $p_i - \sum_{j \in \mathcal{R} \cap row(i)} p_j$
8. set $l = l+1$, $i_l = i$
9. set $\mathcal{R} = \mathcal{R} \backslash \{row(i_l) \cup i_l\}$
10. end while

A/M	**LDU**	$\mathbf{L} \cdot GJ(\mathbf{DU} - \mathbf{B})$	$\mathbf{L} \cdot GJ(\mathbf{D} - \mathbf{B}) \cdot \mathbf{U}$
A^1 / M^1	5	5	5
A^2 / M^1	31	17	36
A^3 / M^1	51	18	40
A^4 / M^1	71	21	51
A^5 / M^1	91	21	59
A^6 / M^1	97	23	63
A^7 / M^1	100	21	64
A^8 / M^1	97	23	70
A^9 / M^1	103	22	65
A^{10} / M^1	100	22	76
A^{11} / M^1	99	22	71

Numbers of BiCGSTAB iterations for the preconditioned nonlinear convection-diffusion problem with preconditioner updated by GJ updates applied to approximate $(\mathbf{D} - \mathbf{B})$ *and* $(\mathbf{DU} - \mathbf{B})$*, respectively.*

Uniform 50 x 50 grid, $\mathbf{M}^{(1)} = ILU(10^{-3})$,

$$\frac{\|\mathbf{I} - \mathbf{L}\|}{\|\mathbf{L}\|} = 0.434 = \frac{\|\mathbf{I} - \mathbf{U}\|}{\|\mathbf{U}\|}\,.$$

A / M	$ILU(10^{-1})$			$ILU(10^{-2})$		
	LDU	**L**GJ(**DU** − **B**)	**L**$triu$(**DU** − **B**)	**LDU**	**L**GJ(**DU** − **B**)	**L**$triu$(**DU** − **B**)
A^1 / M^1	24	24	24	13	13	13
A^2 / M^1	27	26	24	32	20	17
A^3 / M^1	38	27	21	58	23	17
A^4 / M^1	47	25	23	89	24	17
A^5 / M^1	52	22	23	127	23	17
A^6 / M^1	58	21	22	131	24	18
A^7 / M^1	68	22	23	182	25	18
A^8 / M^1	91	24	24	172	26	19
A^9 / M^1	70	20	23	157	22	18
A^{10} / M^1	68	22	24	166	24	18
A^{11} / M^1	76	24	25	163	24	19

Numbers of BiCGSTAB iterations for the preconditioned nonlinear convection-diffusion problem with preconditioner updated by Gauss-Jordan updates applied to (**DU** − **B**) *and triangular updates, respectively*

The sizes of the factors **L** and **U** are for the drop tolerances 10^{-3}, 10^{-2} and 10^{-1} equal to approximately 35000, 12000 and 5000, respectively. The sizes of the GJ updates are in the range $< 6700, 7800 >$ for all tolerances.

3. Coping with possible instabilities

An unlucky choice of $\overline{\mathbf{DU} - \mathbf{B}}$ may be useless for 2 reasons:

- The choice is (close to) singular.
- The decomposition $\mathbf{L}(\overline{\mathbf{DU} - \mathbf{B}})$ is unstable. For triangular updates this may happen whenever the off-diagonal entries of $\mathbf{DU} - \mathbf{B}$ are significantly larger than diagonal entries.

Applying stabilization strategies to the initial system, such as finding a maximal transversal [Benzi, Haws, Tůma - 2000], cannot guarantee to overcome the instability encountered here.

Remedy: Consider the "ideal" update $\mathbf{M}^+ = \mathbf{LDU} - \mathbf{B}$. As $\mathbf{LDU}$ approximates $\mathbf{A}$, we have

$$\mathbf{M}^+ = \mathbf{LDU} - \mathbf{B} \approx \mathbf{A} - \mathbf{B} = \mathbf{A}^+.$$

We may expect $\mathbf{M}^+$ is far from being singular and it inherits diagonal dominance of $\mathbf{A}^+$.

Modify $\mathbf{L}(\overline{\mathbf{DU} - \mathbf{B}})$ as

$$\mathbf{M}^+ = \mathbf{L}\,\overline{(\mathbf{DU} - \mathbf{L}^{-1}\mathbf{B})}, \tag{15}$$

where $\overline{(\mathbf{DU} - \mathbf{L}^{-1}\mathbf{B})}$ is close to $(\mathbf{DU} - \mathbf{L}^{-1}\mathbf{B})$.

Possible choices of $\overline{(\mathbf{DU} - \mathbf{L}^{-1}\mathbf{B})}$:

- $\overline{(\mathbf{DU} - \mathbf{L}^{-1}\mathbf{B})} \equiv \mathbf{DU} - \mathrm{diag}(||\mathbf{L}e_1||, \ldots, ||\mathbf{L}e_n||)^{-1} triu(\mathbf{B})$.

- $\overline{(\mathbf{DU} - \mathbf{L}^{-1}\mathbf{B})} \equiv \mathbf{DU} - triu(\mathbf{L}^{-1}\mathbf{B})$, seems expensive at first sight due to the product $\mathbf{L}^{-1}\mathbf{B}$. But exploiting the sparsity of $\mathbf{B}$, the triangularity of $\mathbf{L}$ and the fact that we need only one triangle of the product, computing $triu(\mathbf{L}^{-1}\mathbf{B})$ can be done effectively.

- $\overline{\mathbf{DU} - \mathbf{L}^{-1}\mathbf{B}} \equiv (\mathbf{DU} - \mathbf{L}^{-1}\mathbf{B})_{[i_1,\ldots,i_l]}$, for a small number of positions i_1 to i_l. It is easy to see that when the positions are chosen to correspond to the nonzero upper subdiagonals of $\mathbf{B}$, then the computation of this approximation of $\mathbf{DU} - \mathbf{L}^{-1}\mathbf{B}$ is comparable to executing one matvec with $\mathbf{B}$.

- Write $(\mathbf{DU} - \mathbf{L}^{-1}\mathbf{B})_{[i_1,\ldots,i_l]}$ as a product of Gauss-Jordan transformations with the algorithm presented before (we allow negative indexes to denote *lower* subdiagonals).

Example: A finite difference analogue of the porous media nonlinear equation [Eisenstat, Walker - 1996] solved over the unit square with zero Dirichlet boundary conditions

$$\nabla u^2 + R\left(\frac{\partial u^3}{\partial x} + f(x,y)\right) = 0. \tag{16}$$

The function $f(x,y)$ is evaluated in order to have the solution $u = x(x-1)y(y-1)$. The initial approximation is a discretization of $u_0(x,y) = 1 - xy$, $R = 50$. We use a uniform 50 x 50 grid.

$Update\_type$	its
$\mathbf{DU} - diag(\mathbf{L}^{-1}\mathbf{B})$	∞
$\mathbf{DU} - triu(\mathbf{L}^{-1}\mathbf{B})$	45
$(\mathbf{DU} - \mathbf{L}^{-1}\mathbf{B})_{[0,1,50]}$	48
$(\mathbf{DU} - \mathbf{L}^{-1}\mathbf{B})_{[0,1]}$	78
$(\mathbf{DU} - \mathbf{L}^{-1}\mathbf{B})_{[0]}$	101
$GJ(\mathbf{DU} - \mathbf{L}^{-1}\mathbf{B})_{[-1:1,50]}$	50
$GJ(\mathbf{DU} - \mathbf{L}^{-1}\mathbf{B})_{[-50,-1:1,50]}$	44
$GJ(\mathbf{DU} - \mathbf{L}^{-1}\mathbf{B})_{[-50,-10:10,50]}$	43

Numbers of iterations for solving the 10th system for different variants of an update of the preconditioner for $\mathbf{A}^{(1)}$ based on triangular and Gauss-Jordan transformations.

The factorization has a much larger number of nonzeros ($\pm$ 100 000) than the original matrix (12300). The size of all the GJ updates is around 7200.

$\mathbf{A}/\ \mathbf{M}$	$\mathbf{LDU}$	$\mathbf{L}GJ(\mathbf{DU}-\mathbf{L}^{-1}\mathbf{B})_{[-50,-1:1,50]}$	$\mathbf{L}(\mathbf{DU}-\mathbf{L}^{-1}\mathbf{B})_{[0,1,50]}$
$\mathbf{A}^{(1)}$ / $\mathbf{M}^{(1)}$	3	3	3
$\mathbf{A}^{(2)}$ / $\mathbf{M}^{(1)}$	7	8	5
$\mathbf{A}^{(3)}$ / $\mathbf{M}^{(1)}$	10	22	11
$\mathbf{A}^{(4)}$ / $\mathbf{M}^{(1)}$	16	14	13
$\mathbf{A}^{(5)}$ / $\mathbf{M}^{(1)}$	26	18	17
$\mathbf{A}^{(6)}$ / $\mathbf{M}^{(1)}$	35	21	20
$\mathbf{A}^{(7)}$ / $\mathbf{M}^{(1)}$	51	29	25
$\mathbf{A}^{(8)}$ / $\mathbf{M}^{(1)}$	51	32	33
$\mathbf{A}^{(9)}$ / $\mathbf{M}^{(1)}$	∞	50	43
$\mathbf{A}^{(10)}$ / $\mathbf{M}^{(1)}$	∞	45	49
$\mathbf{A}^{(11)}$ / $\mathbf{M}^{(1)}$	∞	40	39
$\mathbf{A}^{(12)}$ / $\mathbf{M}^{(1)}$	∞	44	42
$\mathbf{A}^{(13)}$ / $\mathbf{M}^{(1)}$	∞	39	44
$\mathbf{A}^{(14)}$ / $\mathbf{M}^{(1)}$	∞	44	44
$\mathbf{A}^{(15)}$ / $\mathbf{M}^{(1)}$	∞	39	43
$\mathbf{A}^{(16)}$ / $\mathbf{M}^{(1)}$	∞	43	48

Numbers of BiCGSTAB iterations

Related/Future issues:

- We performed also some experiments where our nonlinear problems where discretized by upwind schemes, leading to triangular difference matrices. The results for solving the linear problems were rather good, but we typically needed more nonlinear iterations.

- An interesting problem is to choose triangular updates which correspond to the sparsity pattern and sizes of entries of the difference matrix *differently* for each system. A closely related problem is to find a nonsymmetric permutation which would transform the system matrices into a form which is more suitable for our updates.

More details can be found in ,,Preconditioner updates for solving sequences of large and sparse nonsymmetric linear systems" [Duintjer Tebbens, Tůma - submitted to SISC in 2005].

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