

Contents

Nomenclature	xv
Notation	xvii
1. Introduction	1
1.1. Motivation	1
1.2. Related work	4
1.2.1. Embedded method	4
1.2.2. Partitioned coupling	5
1.3. Aim of this work	7
1.4. Outline	7
2. Fluid dynamic equations	9
2.1. Compressible viscid Navier-Stokes equations	9
2.1.1. Boundary conditions	11
2.2. Compressible inviscid Euler equations	12
2.2.1. Boundary conditions	12
2.3. Linearized Euler equations	13
2.3.1. Boundary conditions	13
3. Discretization in space and time	15
3.1. Spatial discretization - Discontinuous Galerkin method	16
3.1.1. Compressible inviscid Euler equations	16
3.1.2. Compressible viscous Navier-Stokes equations	19
3.2. Explicit time discretization - Runge-Kutta method	23
3.3. Numerical oscillations - Gibbs oscillation	24
4. Numerical Framework	29
4.1. <i>APES</i> simulation framework	29
4.1.1. High-order Discontinuous Galerkin solver - <i>Ateles</i>	31
4.1.2. Integrated coupling approach - <i>APESmate</i>	32
4.2. External coupling approach - <i>preCICE</i>	33
5. Embedded boundary method	35
5.1. State of the art - Geometry representation	36

5.2. Volume penalization method - Brinkman penalization . . .	38
5.3. Representation of the masking function χ in high-order Discontinuous Galerkin	41
5.4. Evaluation of the masking function χ in the numerical scheme	43
5.5. Over-integration - Cost estimation	50
5.6. Specification of the masking function χ	52
5.7. Implicit-mixed-explicit Runge-Kutta method	54
6. Validation of the moving geometry	61
6.1. Convergence study - Acoustic pulse	62
6.2. Shock capturing - Shock-wall interaction	68
6.2.1. Interaction of a shock wave with a non-moving wall .	68
6.2.2. Interaction of a shock wave with a moving wall . . .	75
6.3. Shock formation - Moving piston	80
6.4. Curved boundary - Moving cylinder	88
6.5. Sharp boundary - Supersonic moving wedge	96
6.6. Reduced computation inside the geometry	101
6.7. Scalability and computational cost of the embedded method	105
6.7.1. Scalability of the embedded method	105
6.7.2. Computational cost of the embedded method	106
7. Multi-scale problems - An efficient strategy	117
7.1. State of the art - Coupled problems	118
7.2. Partitioned coupling	120
7.3. Quality of the solution - Data mapping	121
7.3.1. Interpolation	122
7.3.2. Data mapping by evaluation	125
7.3.3. Error investigation	126
8. Load balancing - Coupled multi-scale problems	141
8.1. Intra-subdomain	142
8.2. SPartA algorithm	145
8.3. Inter-subdomain	147
8.4. Optimization of the gradient computation	148
8.5. Load balancing for a 3-field coupled simulation	151
9. Application examples - Complex moving geometries	157
9.1. Numerical results - Moving geometry	157
9.1.1. Supersonic flow - Moving cylinder	158
9.1.2. Rotating airfoil	162
9.1.3. Collision of two moving spheres	164

9.1.4. Collision of three moving Spheres	168
9.1.5. Rotating fan	171
9.2. Performance results - Moving geometry	174
9.2.1. Rotating fan	174
9.2.2. Collision of three moving Spheres	179
10. Numerical results - Coupled 3-field simulation	181
10.1. Innermost subdomain: Compressible Navier-Stokes	188
10.2. Innermost and middle subdomain: Compressible Navier-Stokes and Euler	195
10.3. Innermost, middle and outermost subdomain: Navier-Stokes, Euler and Linearized Euler	201
10.4. Coupling interfaces of the 3-field coupled simulation	209
10.5. Performance	213
11. Conclusion	217
A. Appendix	221
A.1. Multi-scale simulations - Partitioned coupling with <i>preCICE</i>	221
A.2. Reduced computation inside the geometry - Code	223
A.3. Sharp boundary - Supersonic moving wedge	224
A.4. Sponge - Reduced boundary reflections	229
Bibliography	233
List of Figures	243
List of Tables	257