

# Some examples of structure preservation

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Structure preserving algorithms attempt to preserve the integrity of inherent physical or geometric properties.

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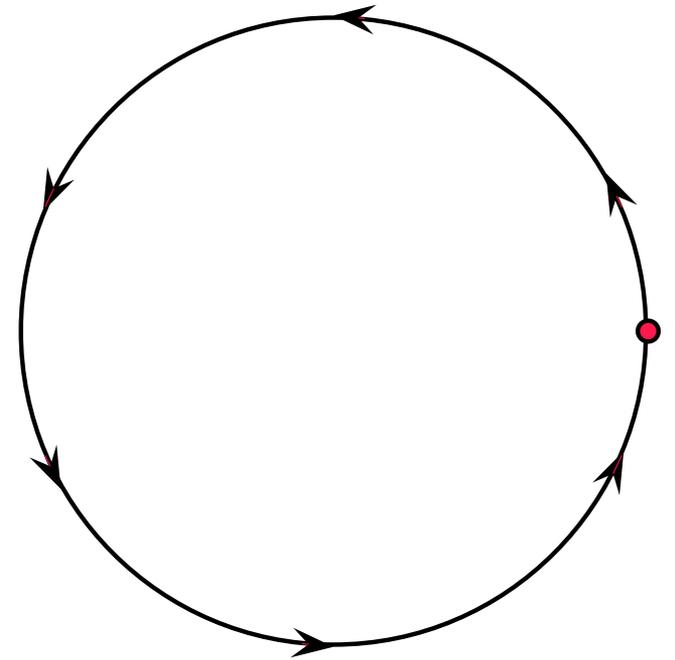
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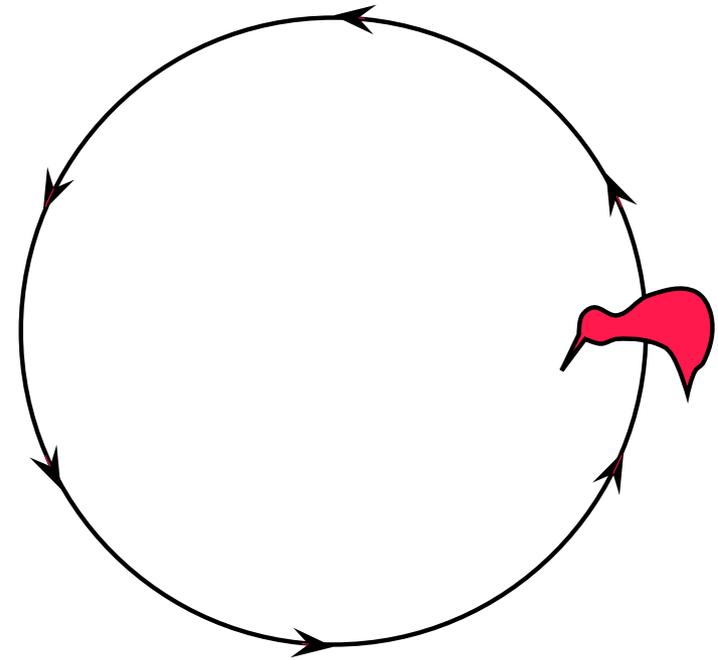
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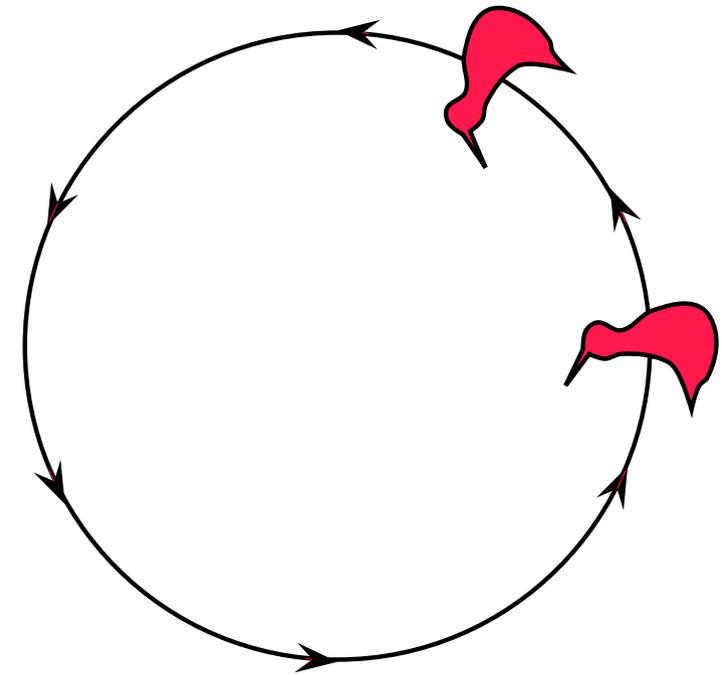
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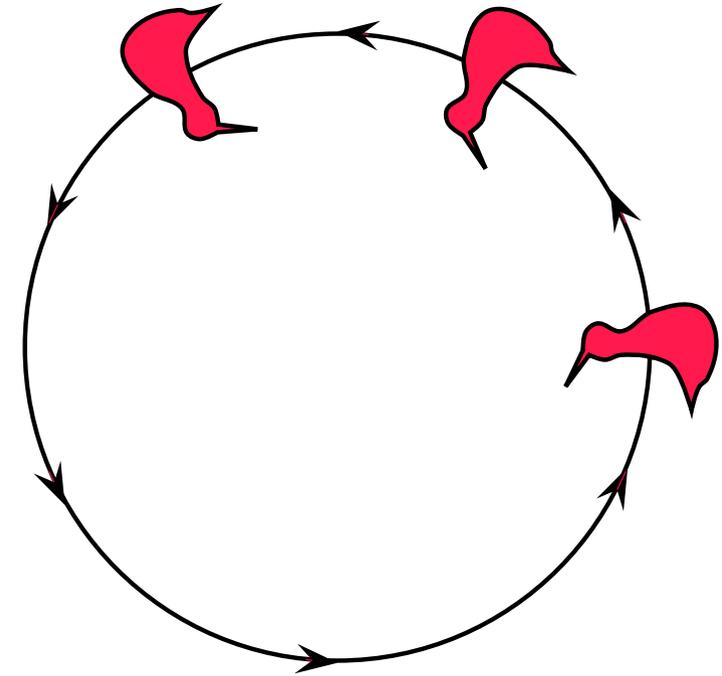
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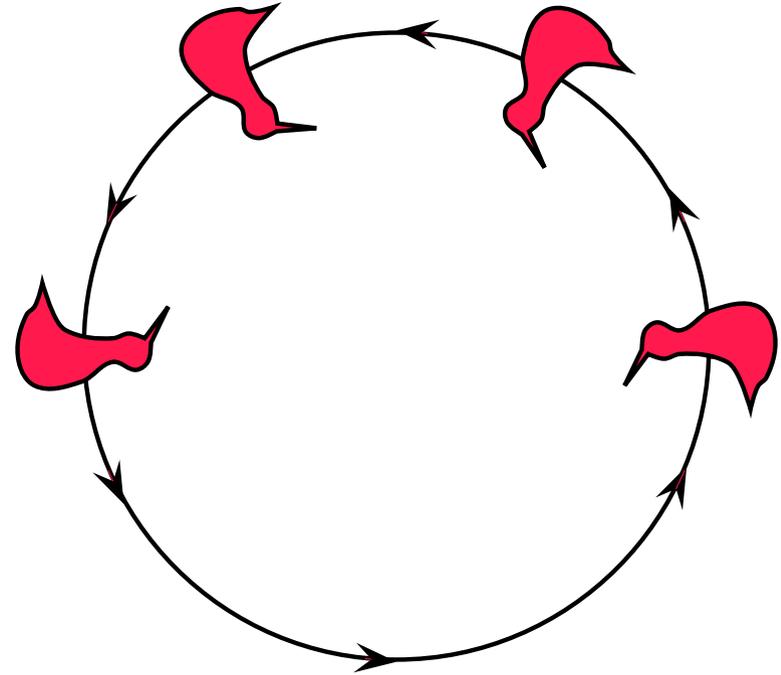
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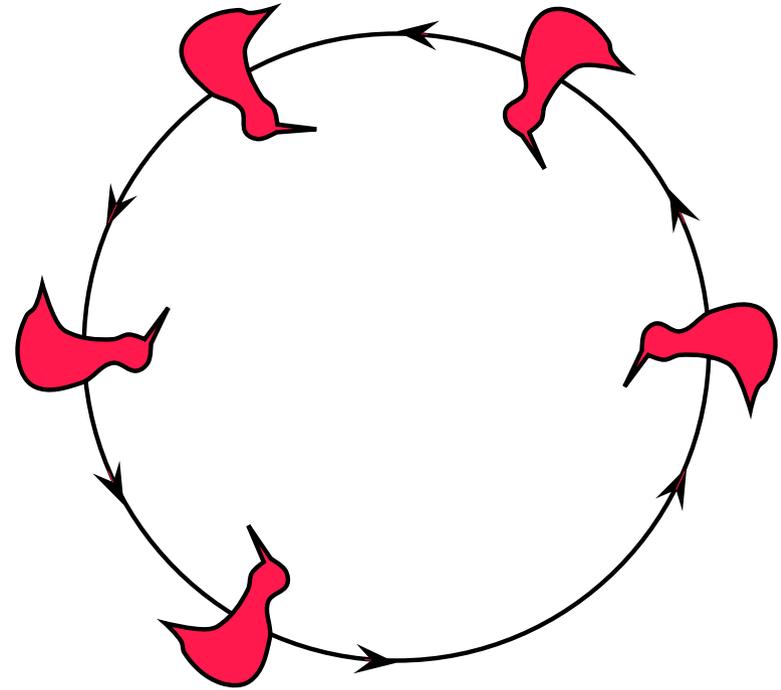
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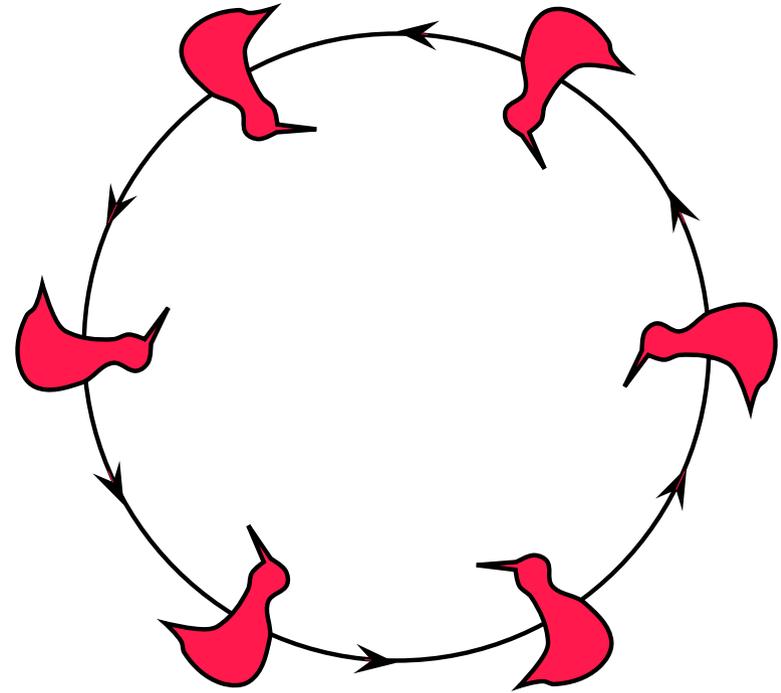
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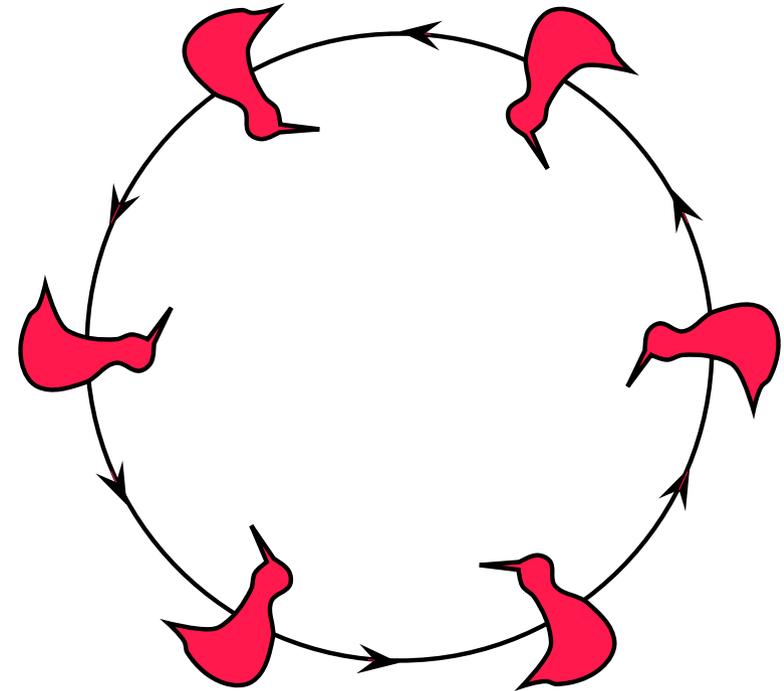
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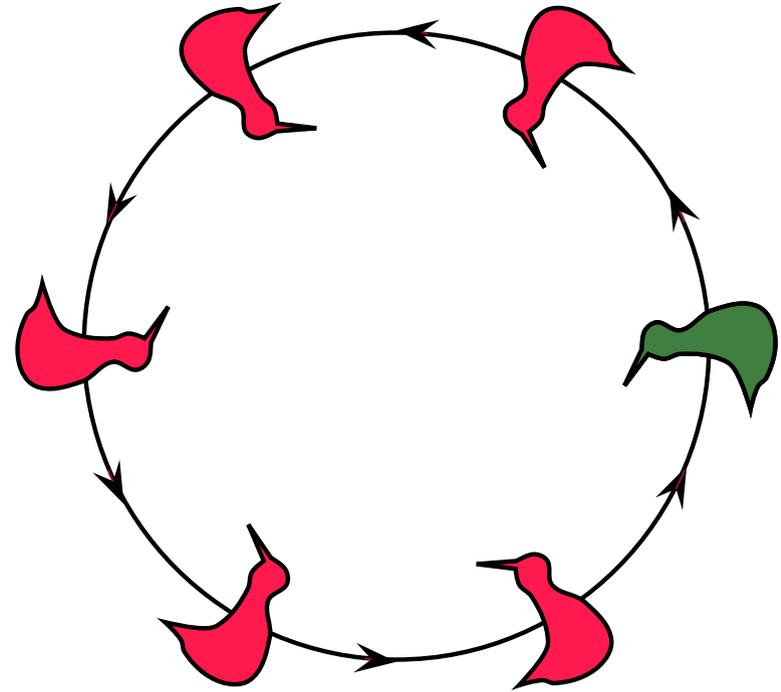
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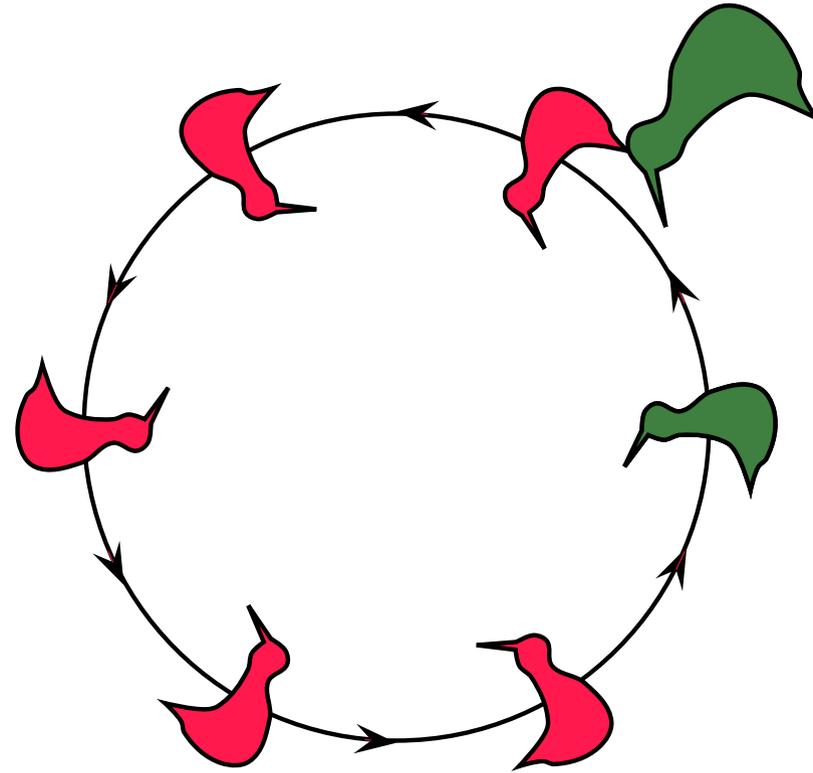
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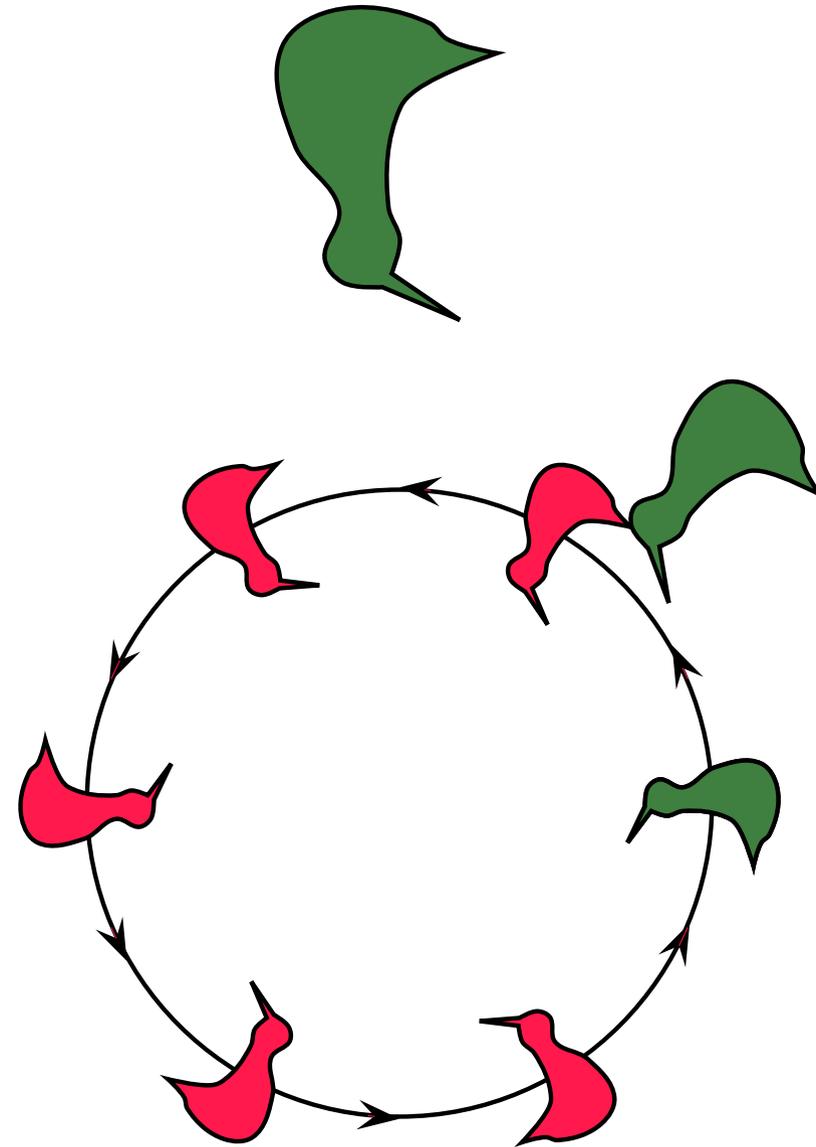
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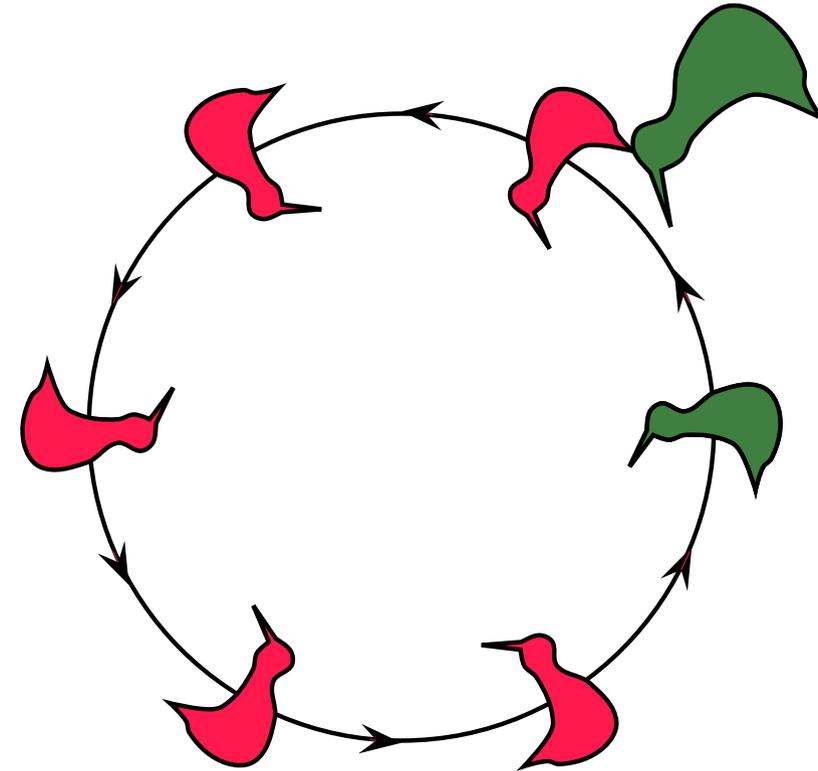
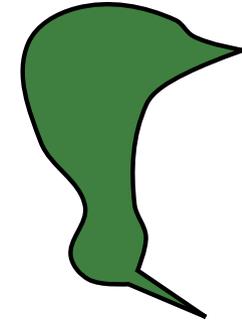
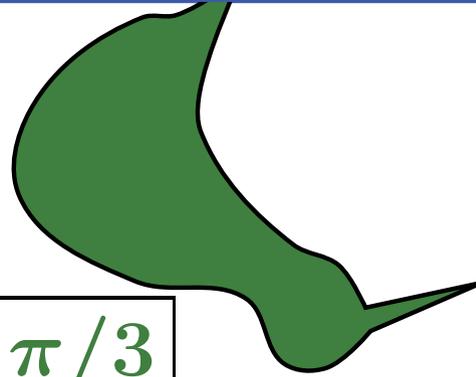
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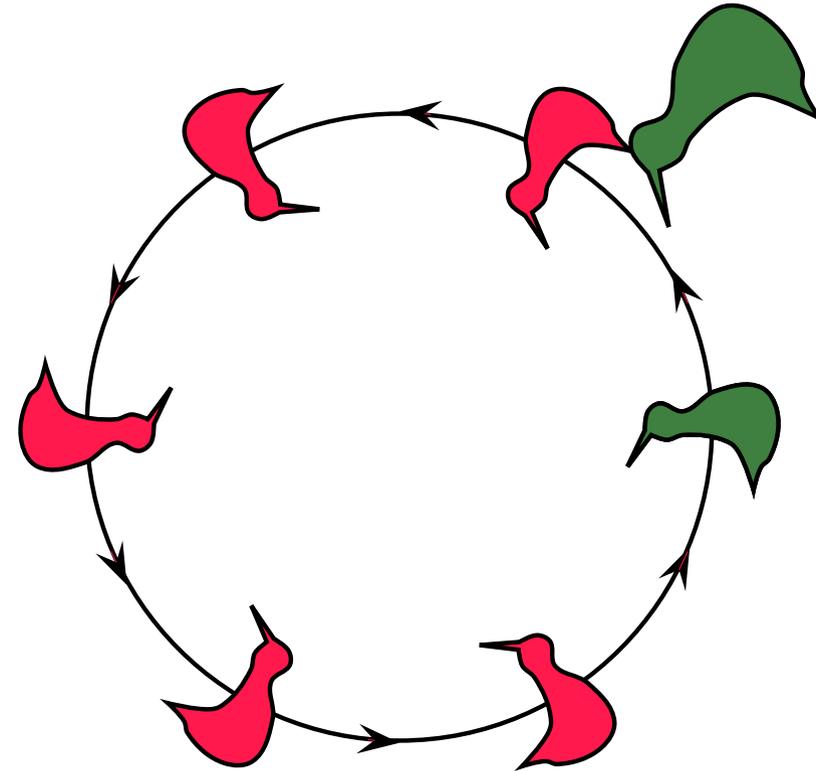
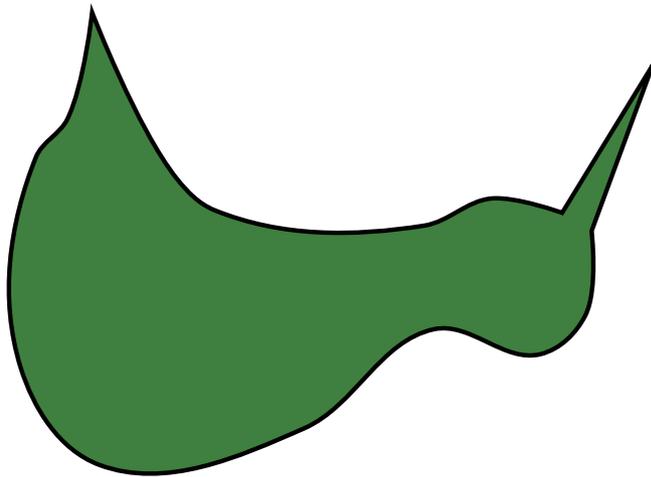
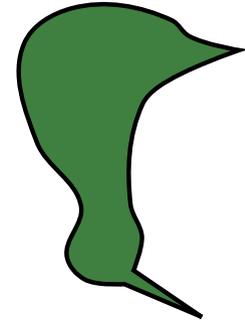
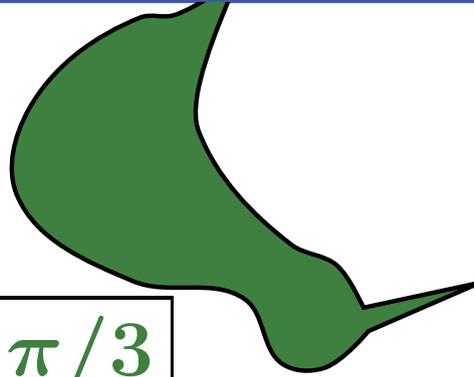
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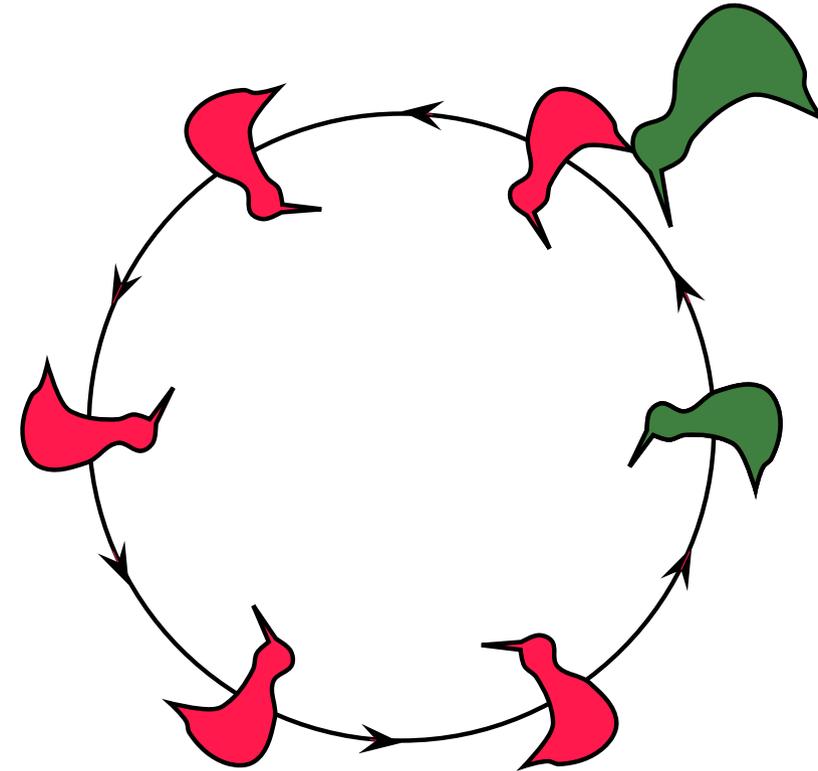
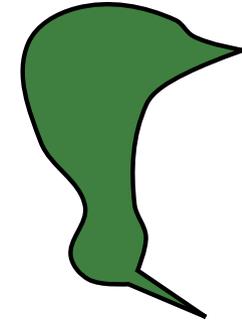
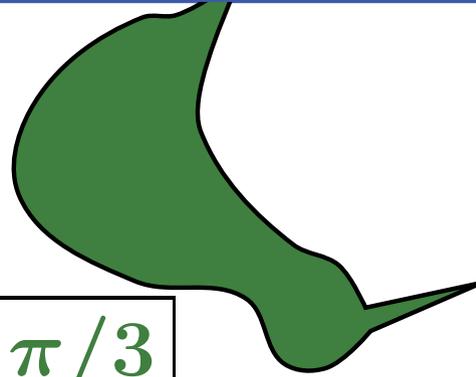
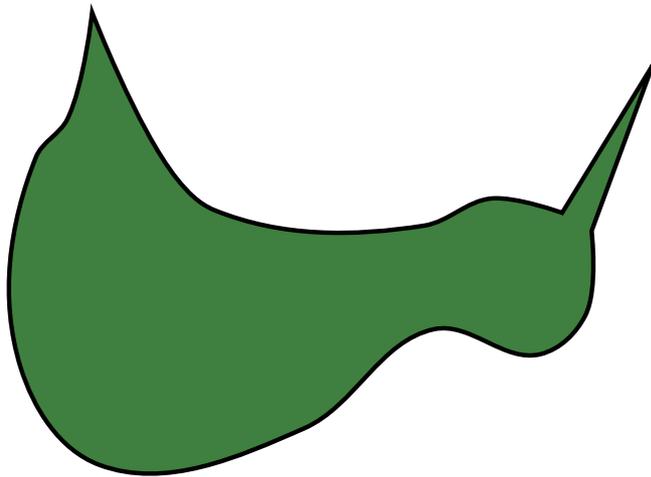


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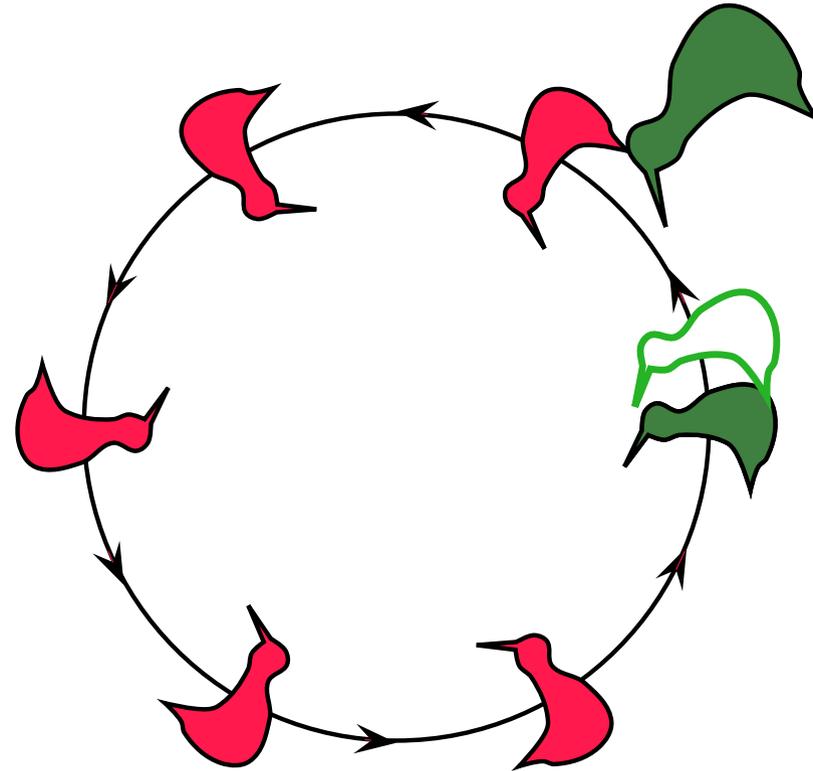
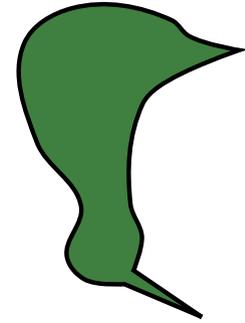
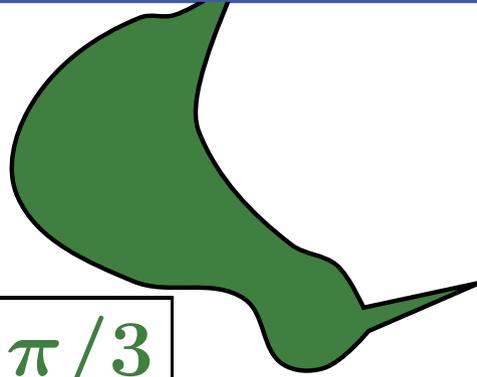
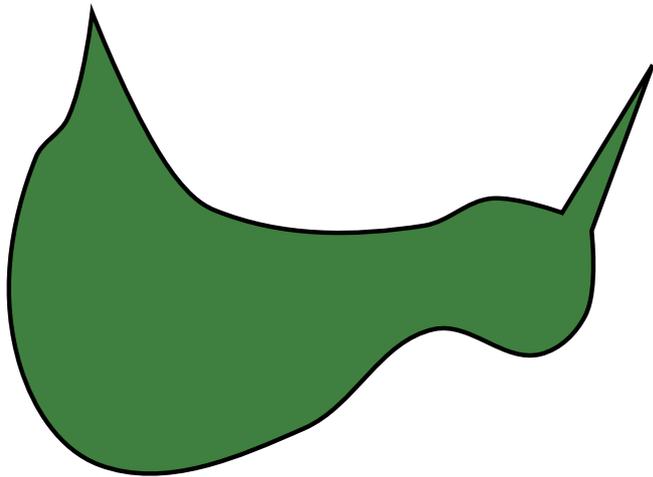


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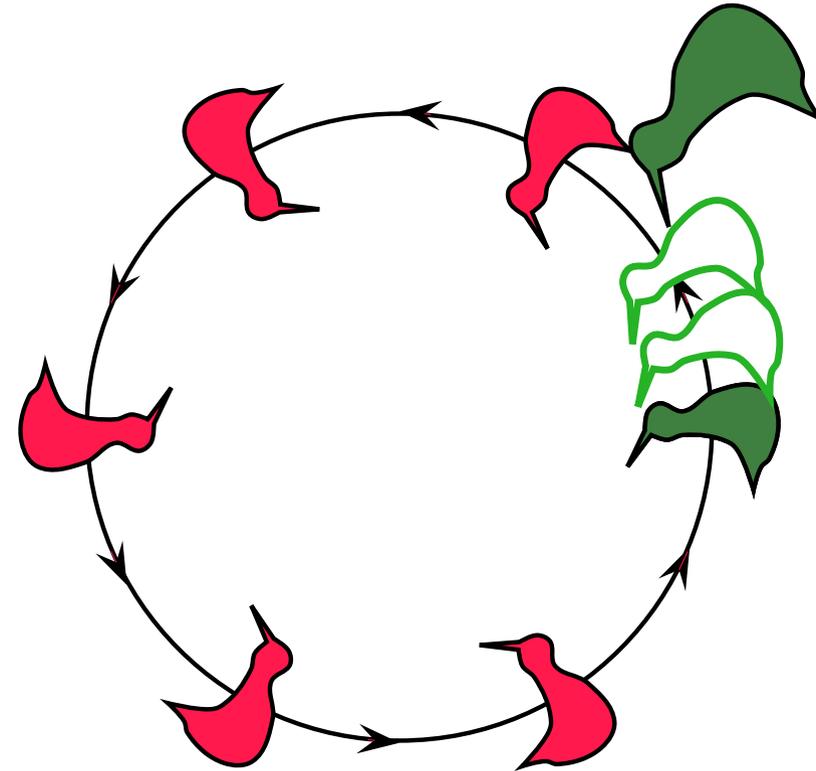
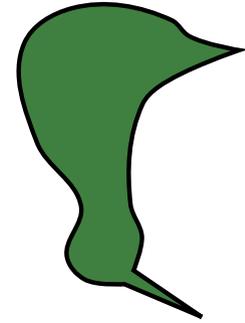
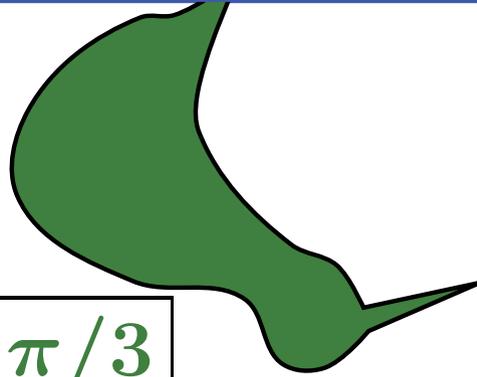
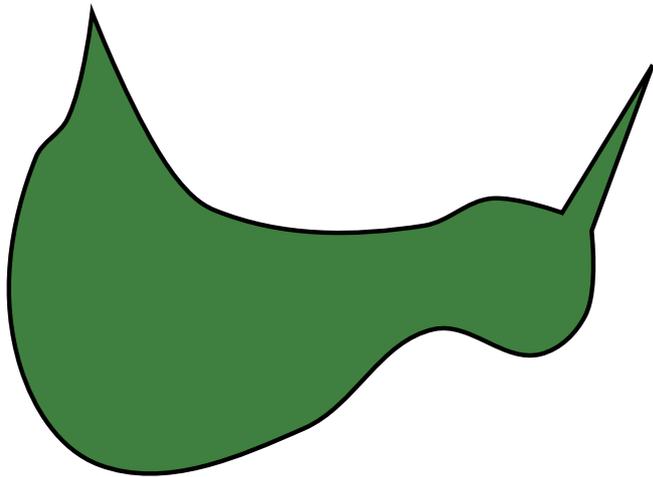


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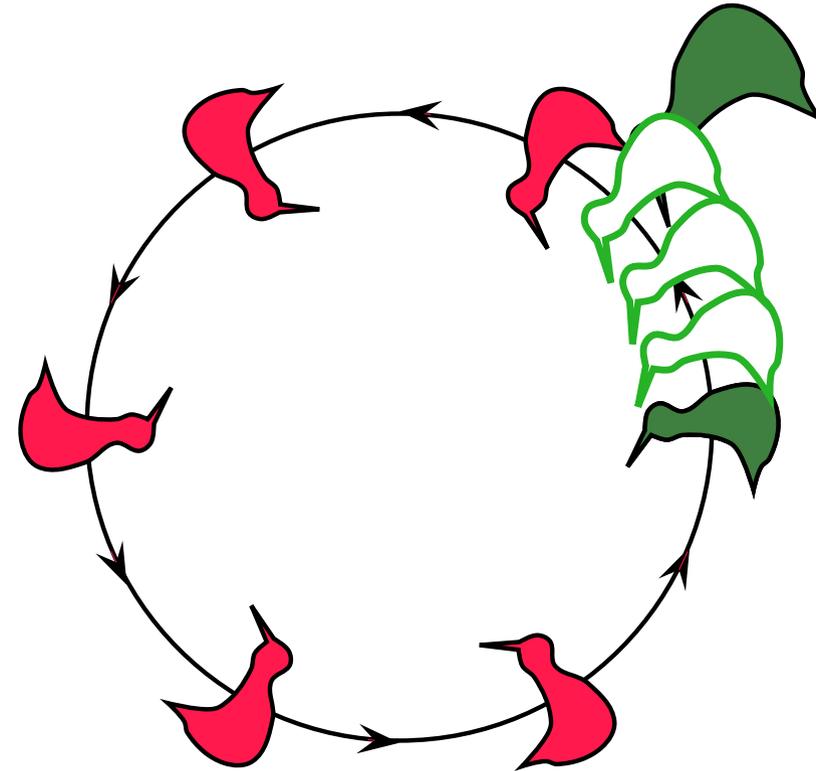
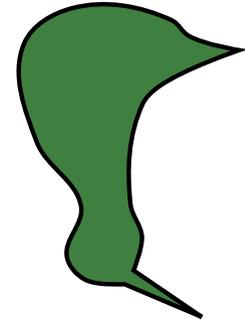
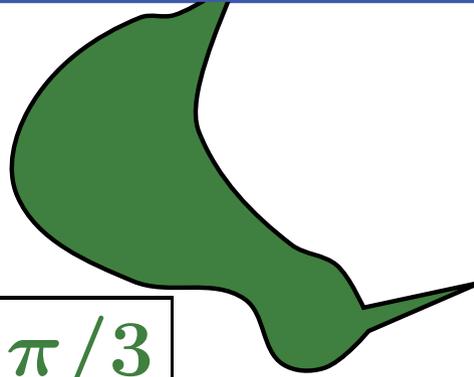
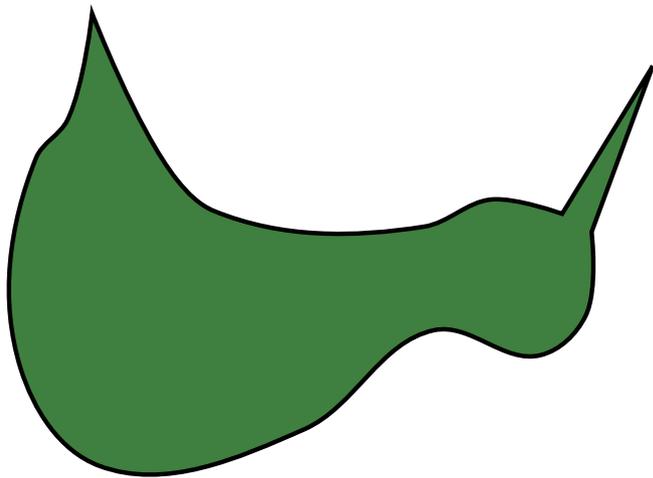


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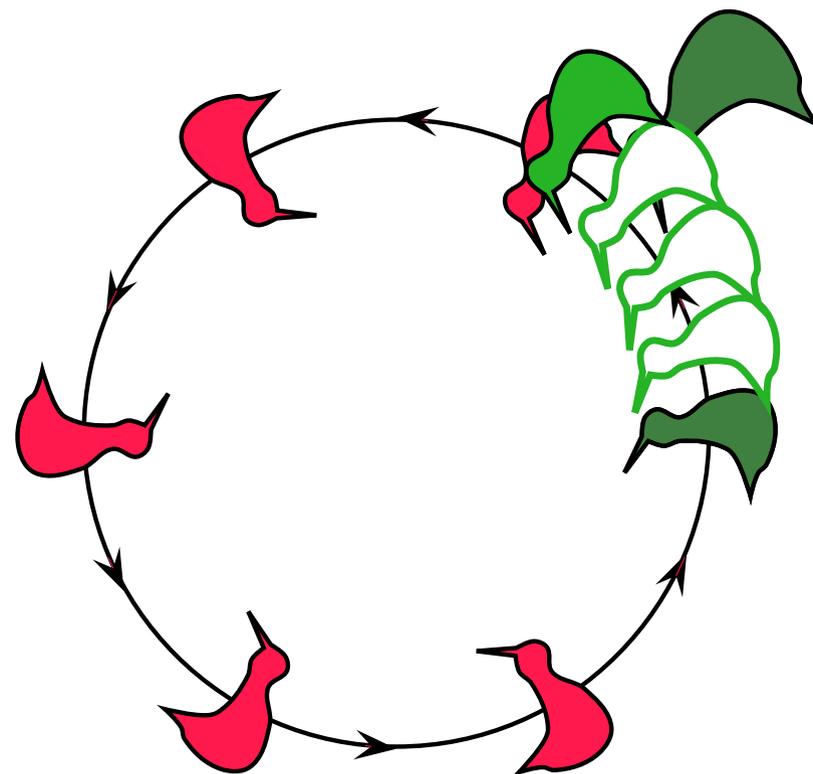
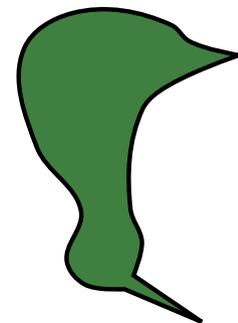
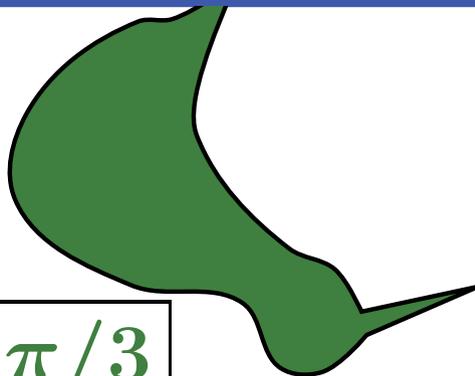
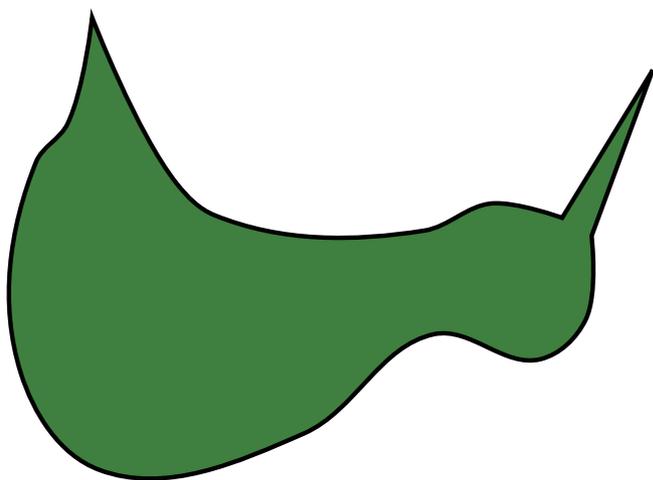


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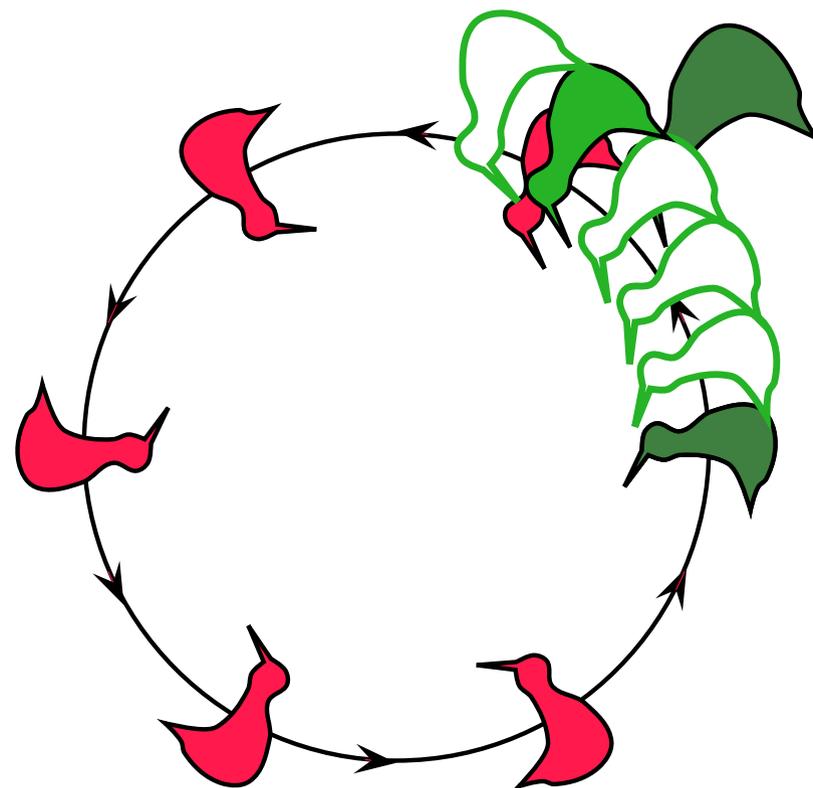
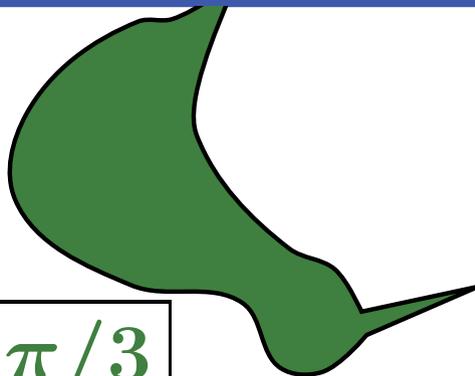
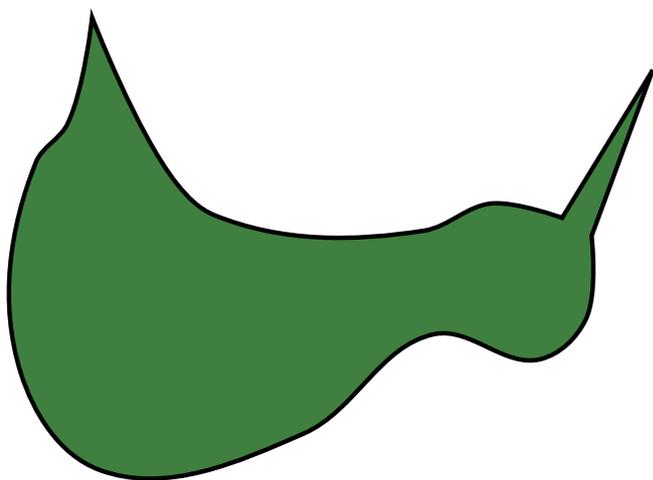


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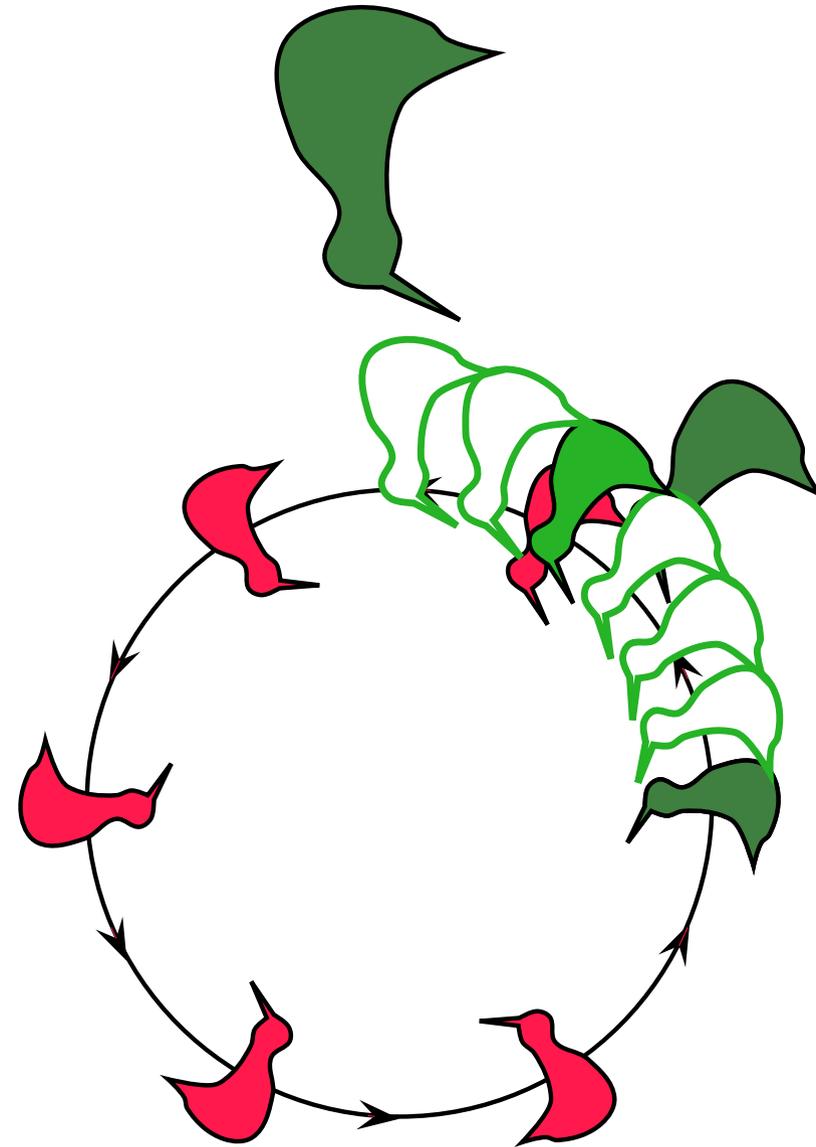
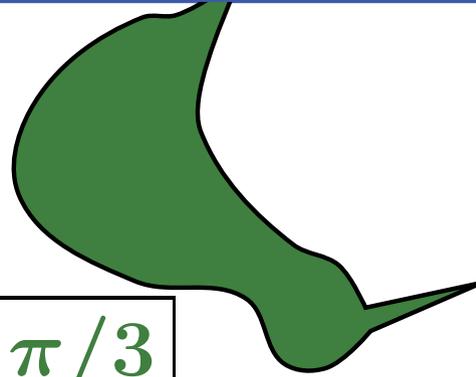
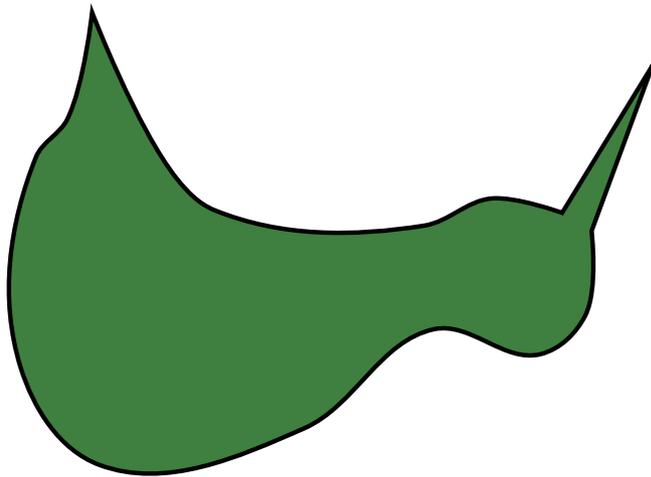


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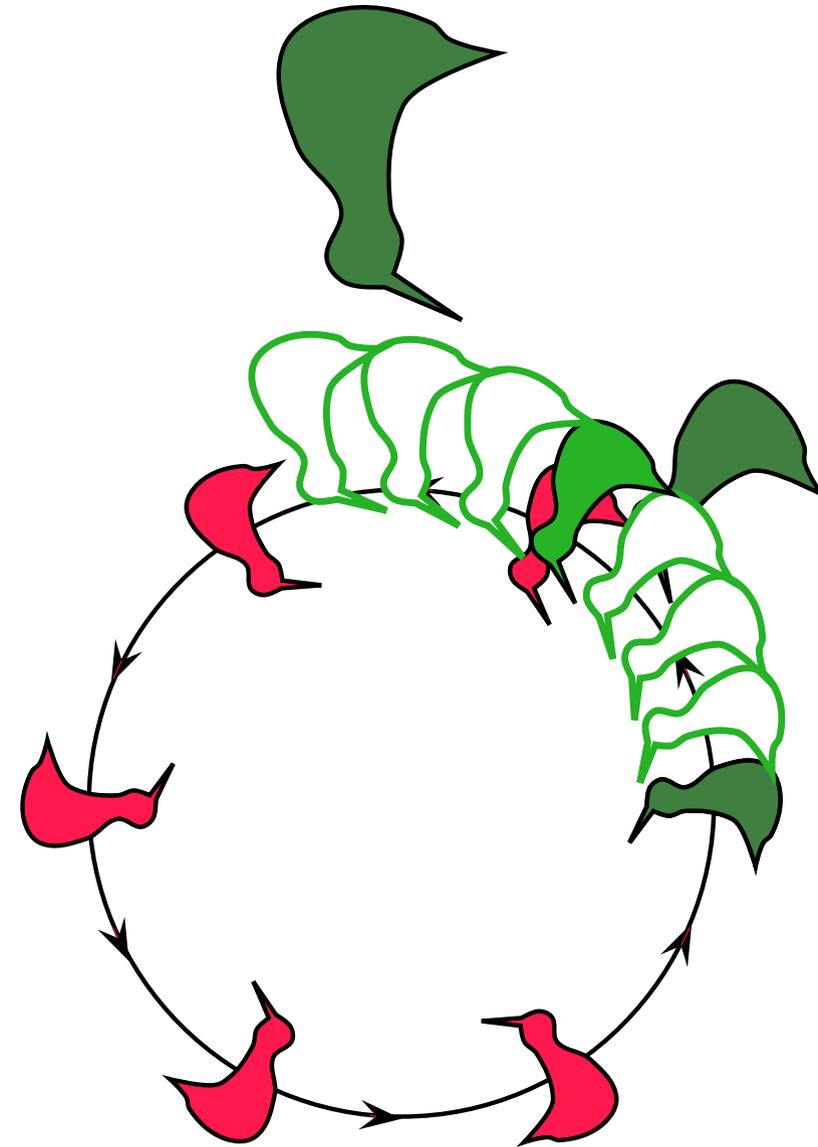
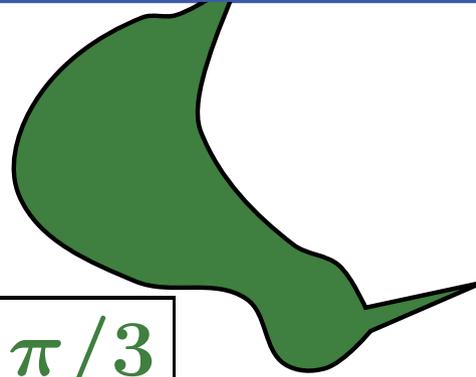
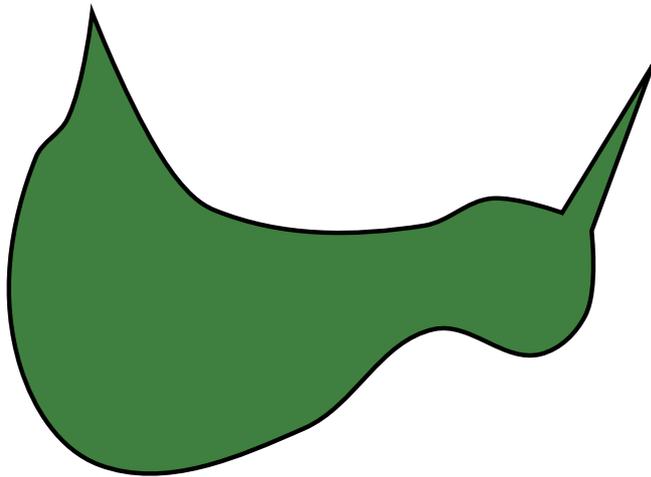


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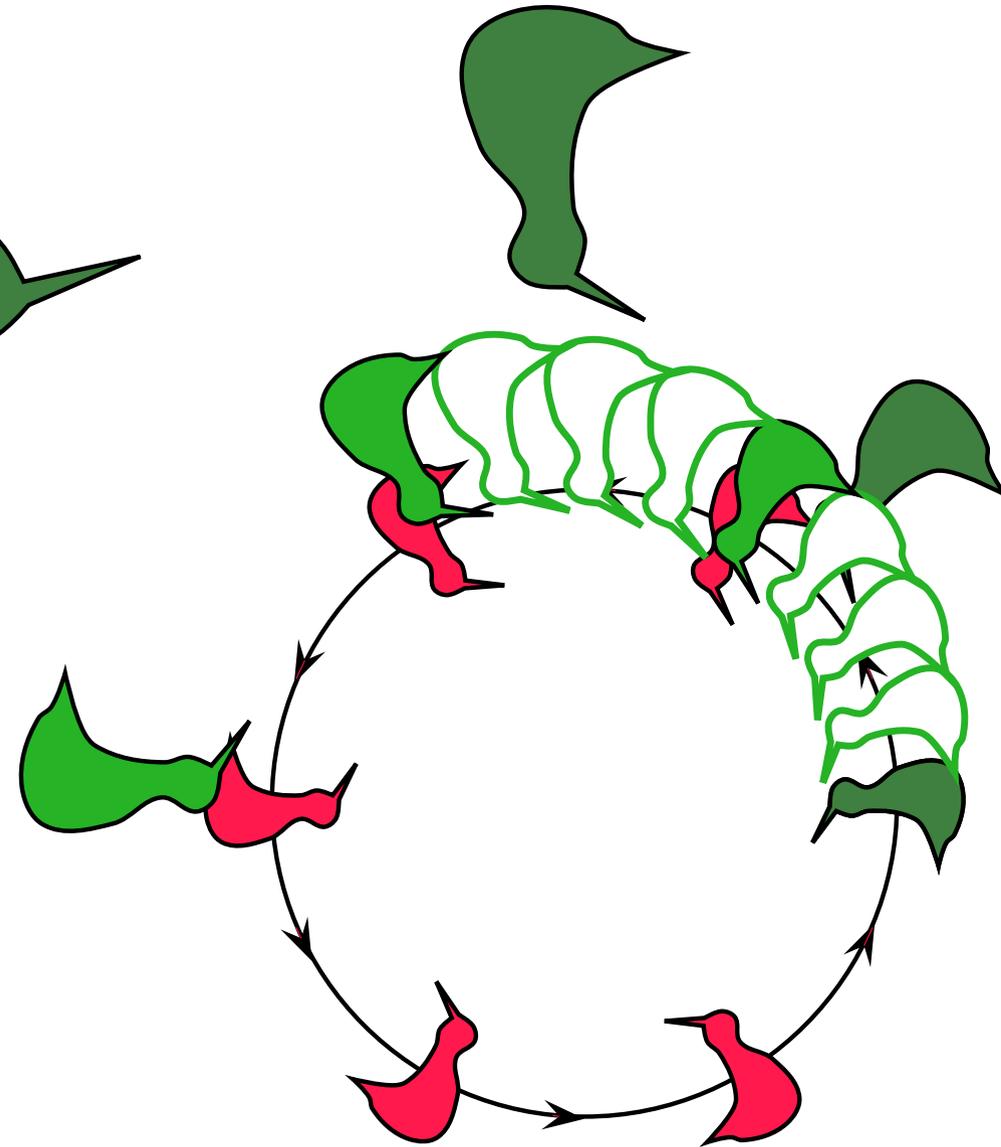
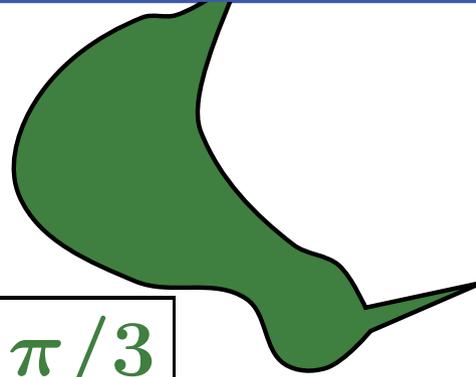
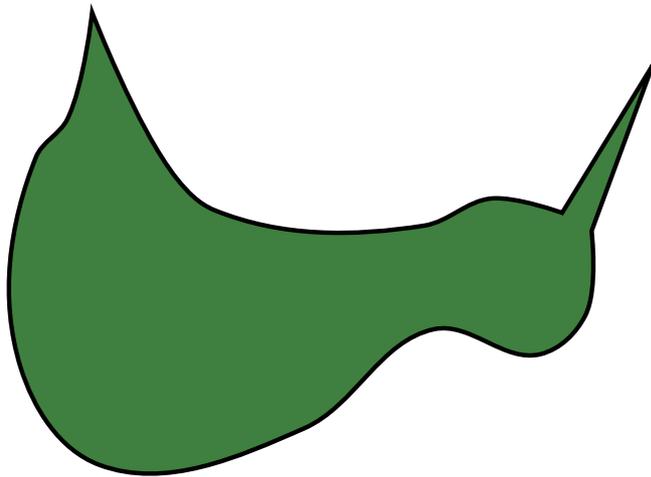


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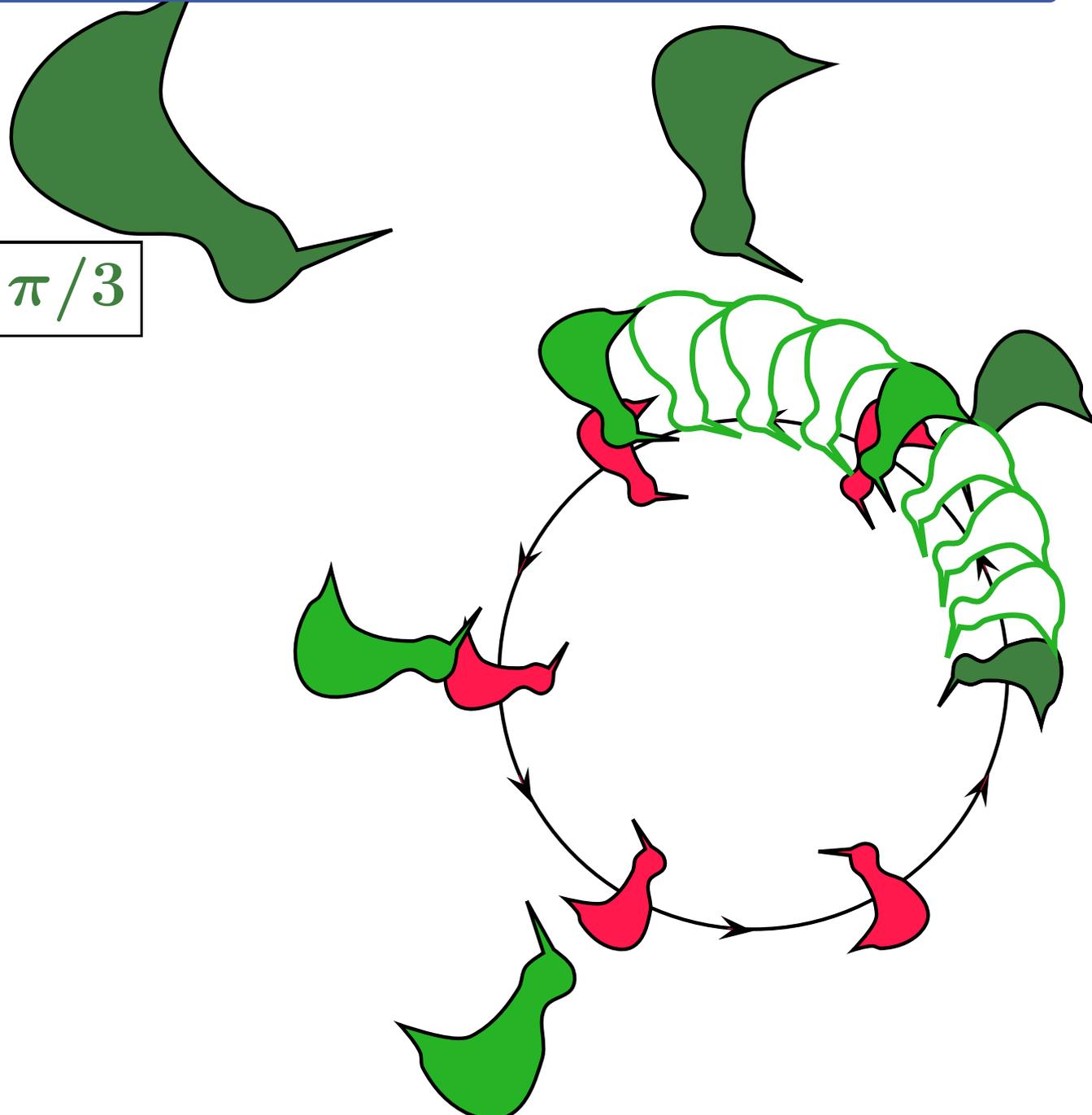
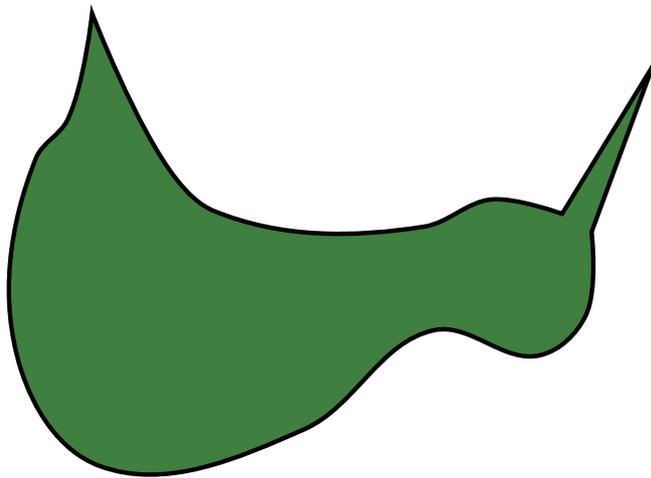


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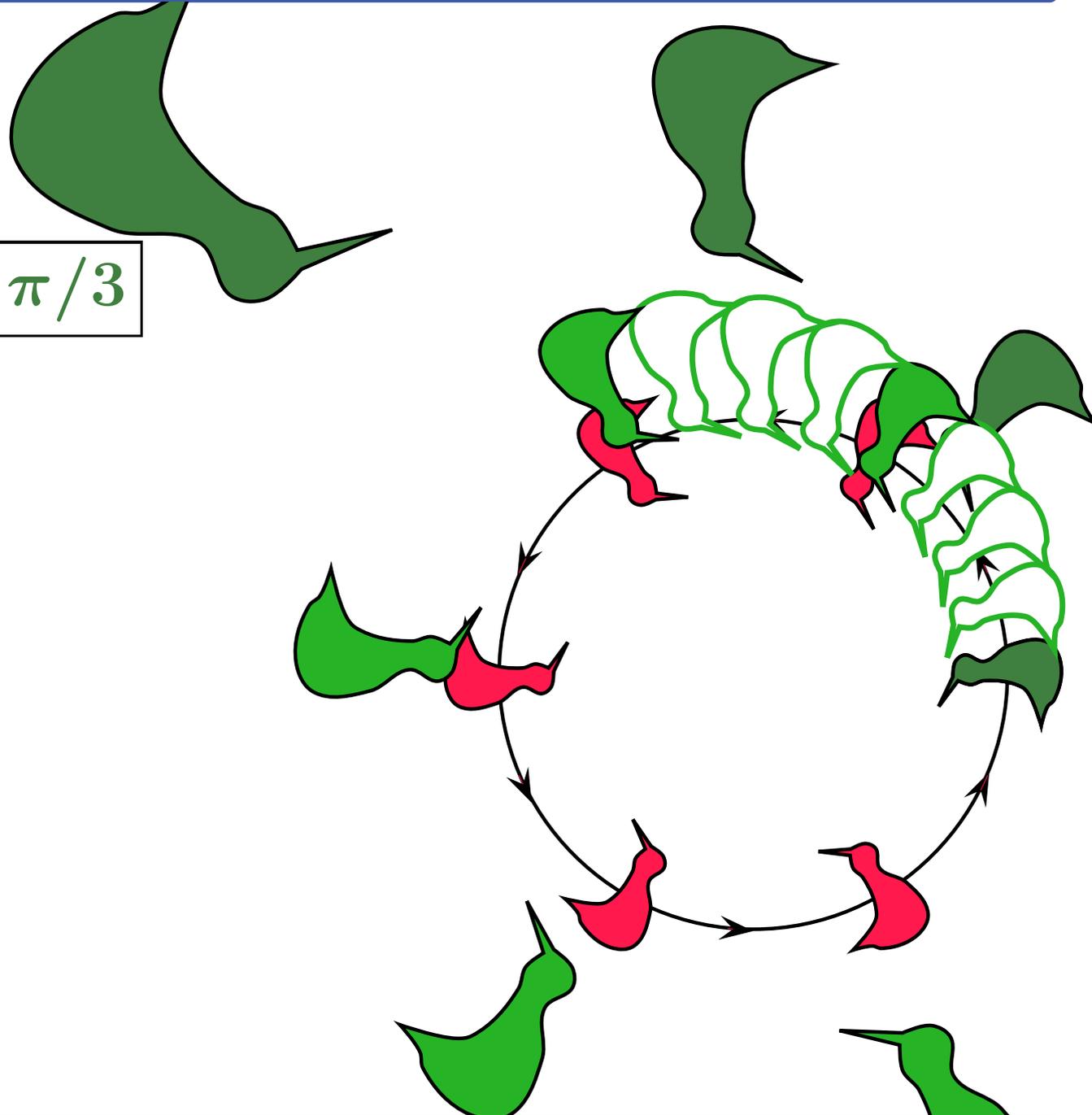
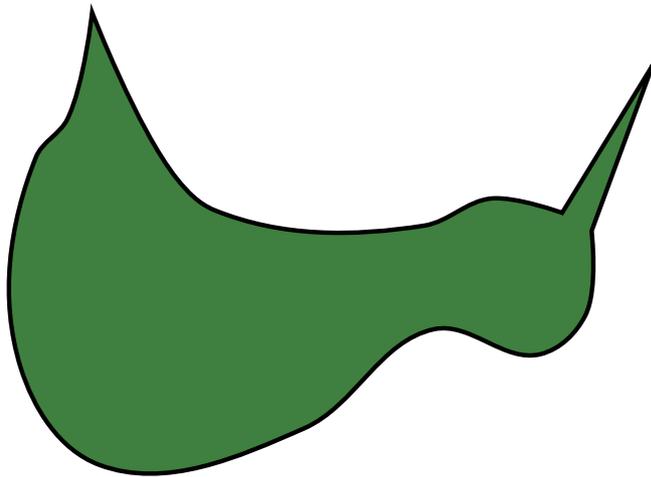


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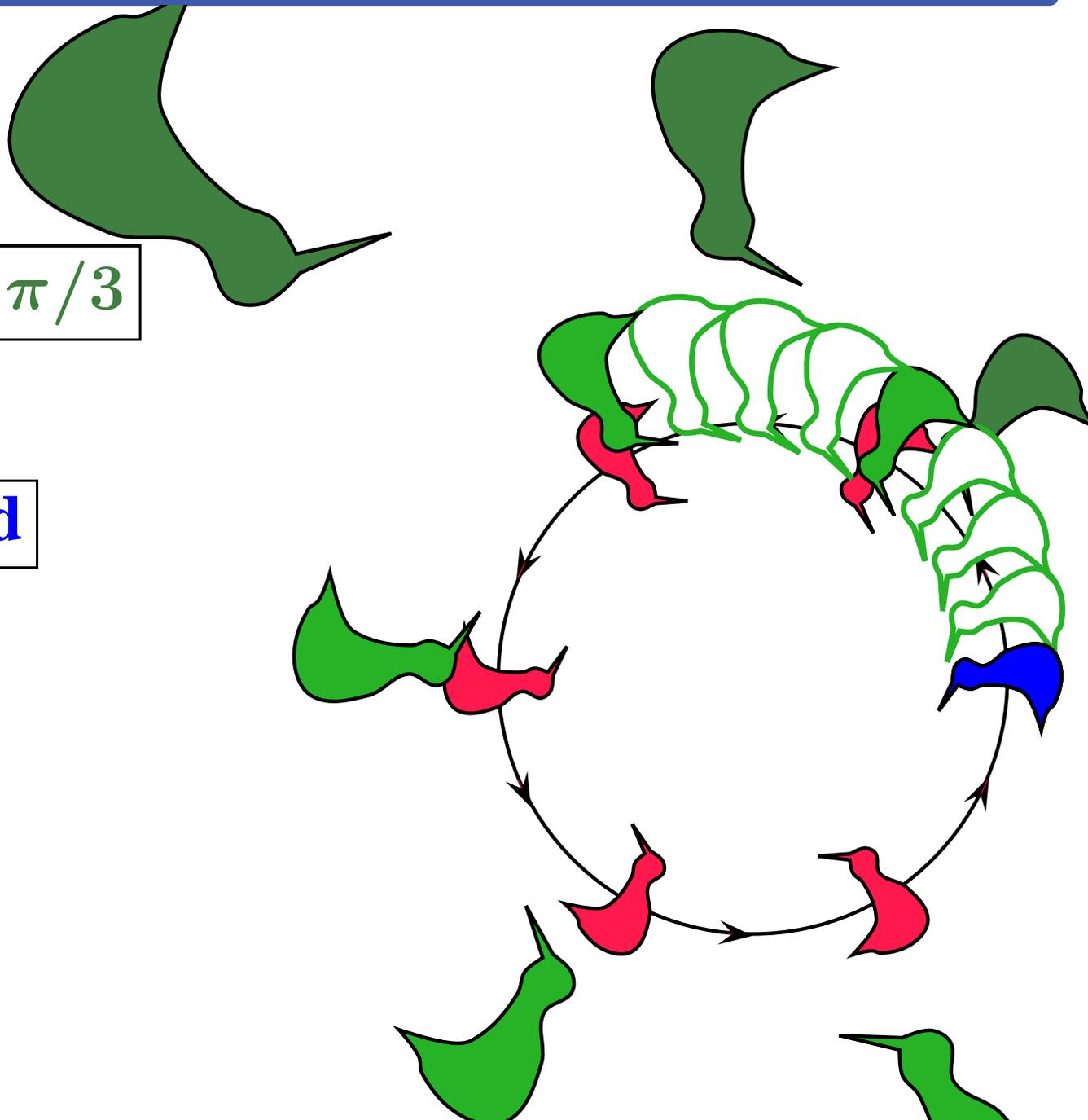
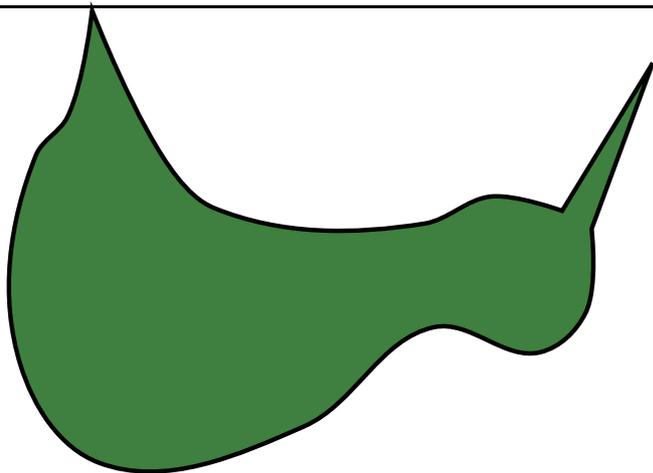
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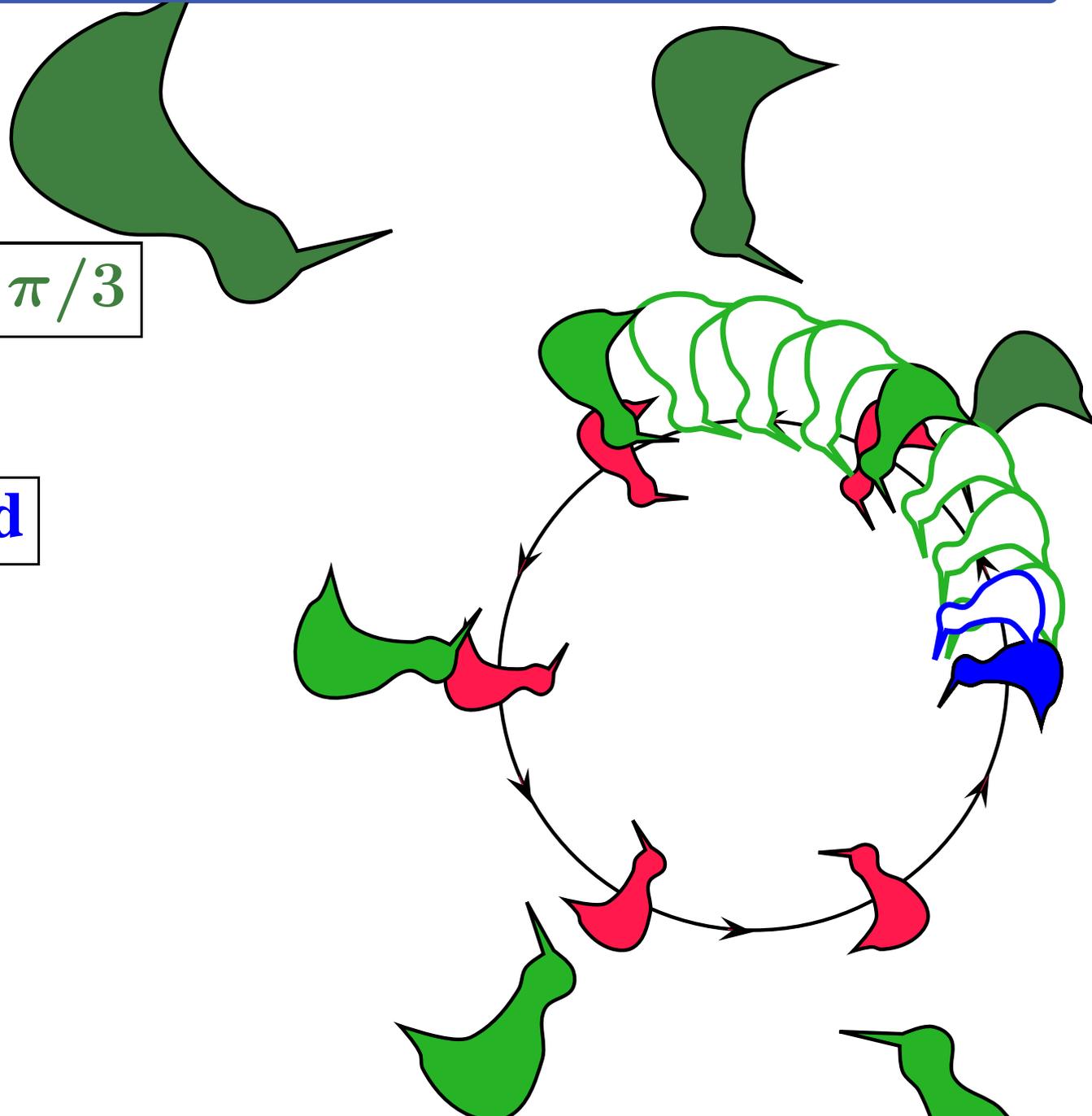
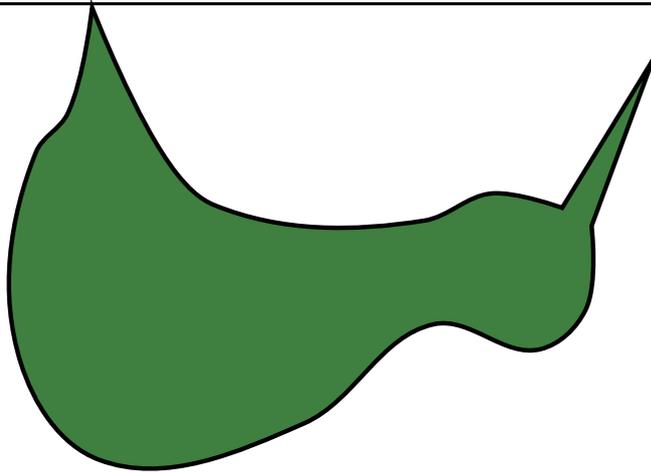
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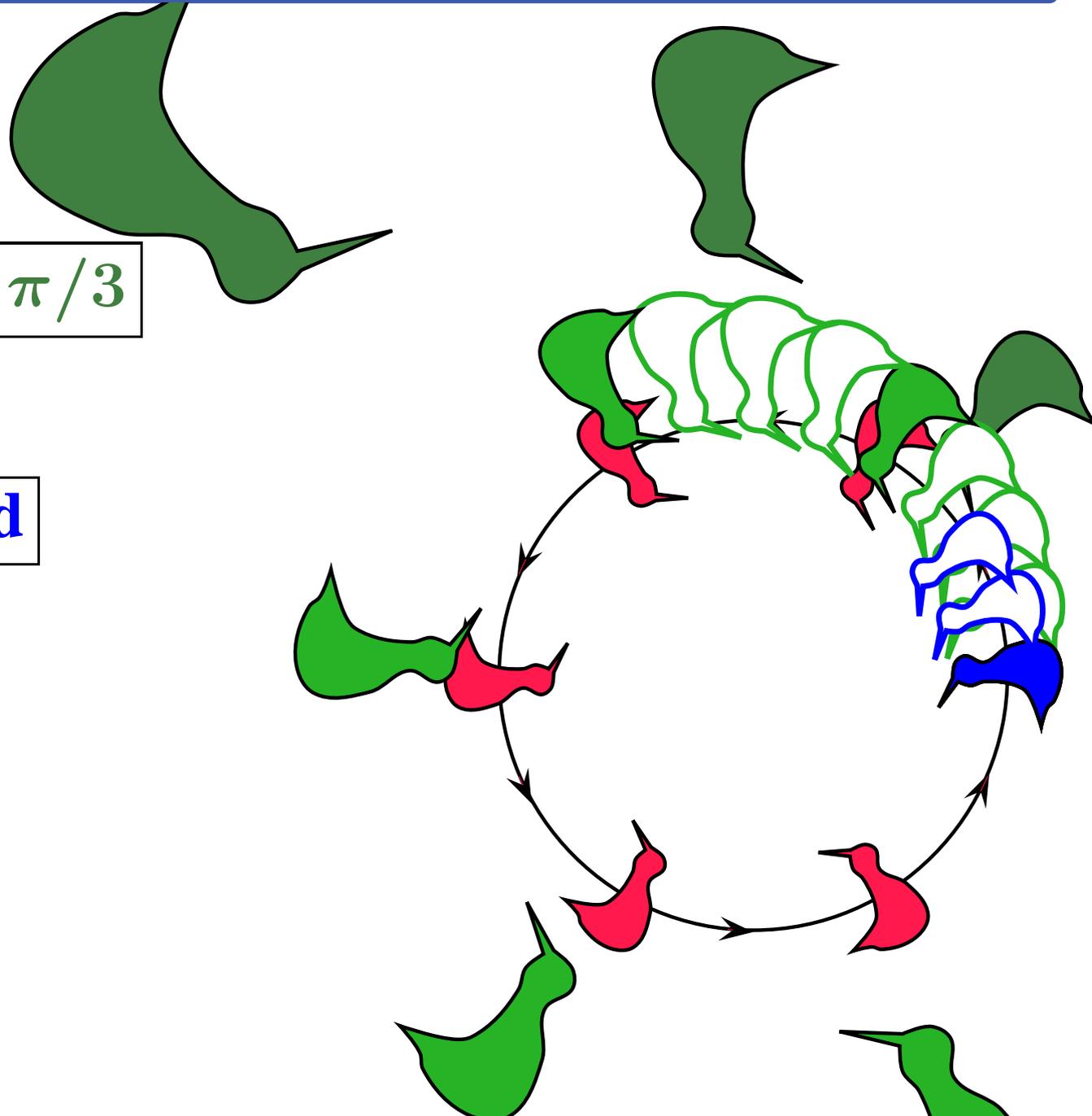
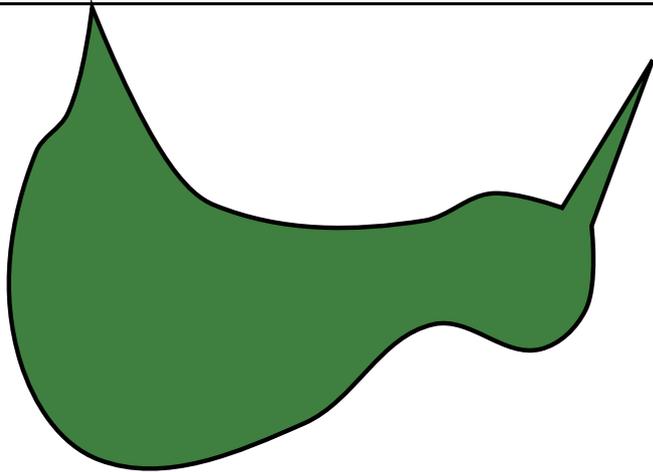
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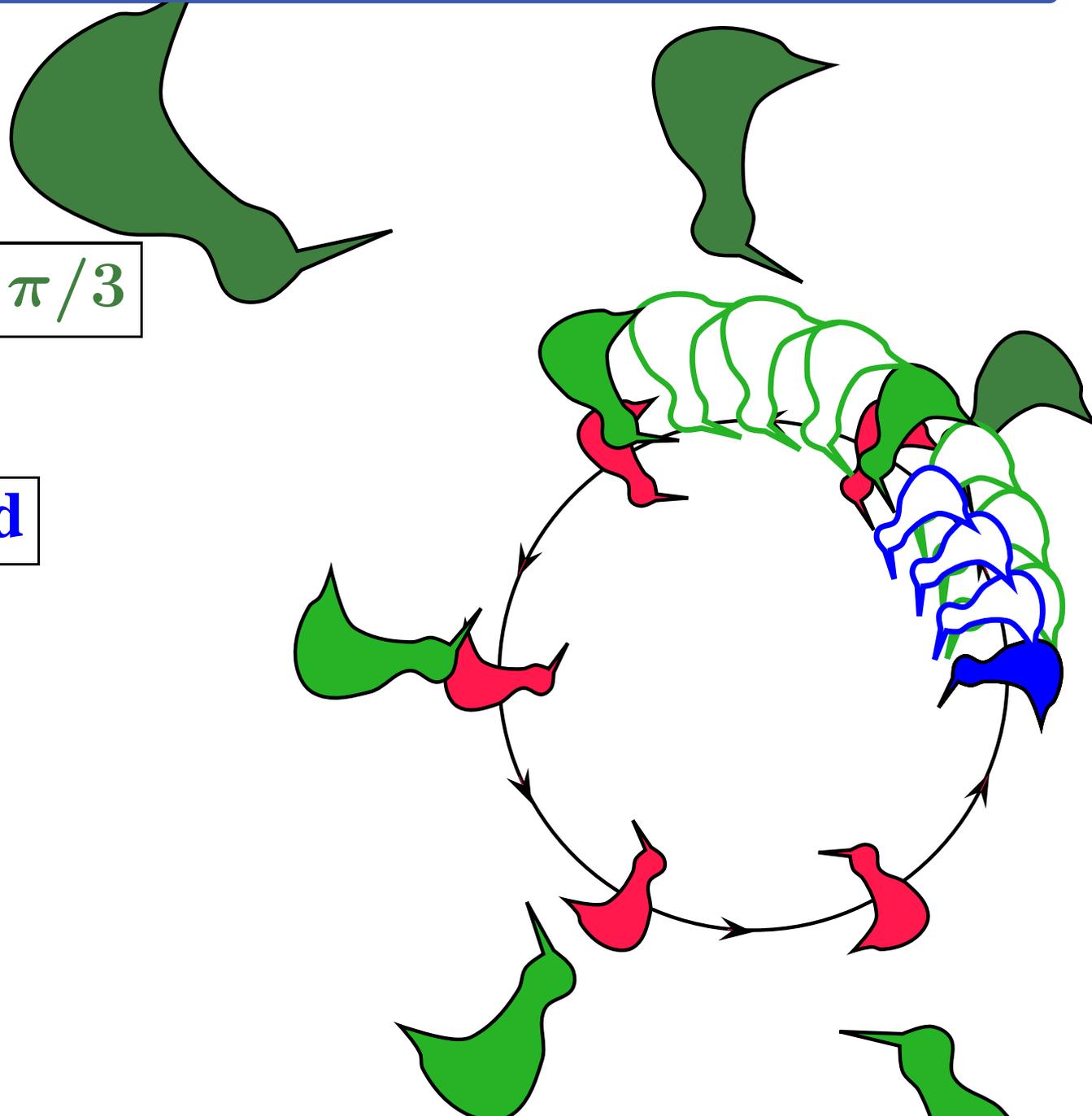
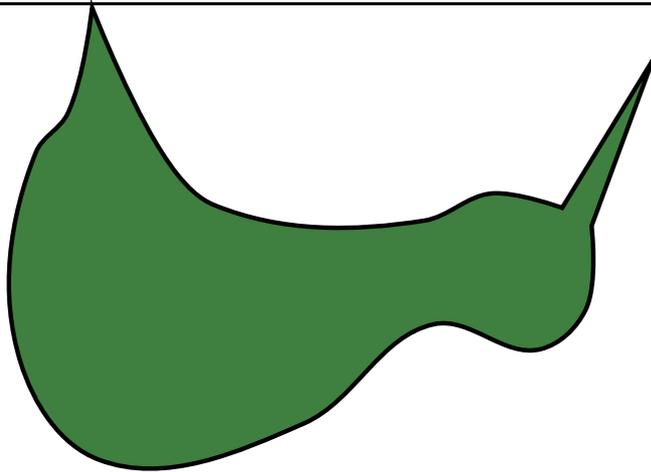
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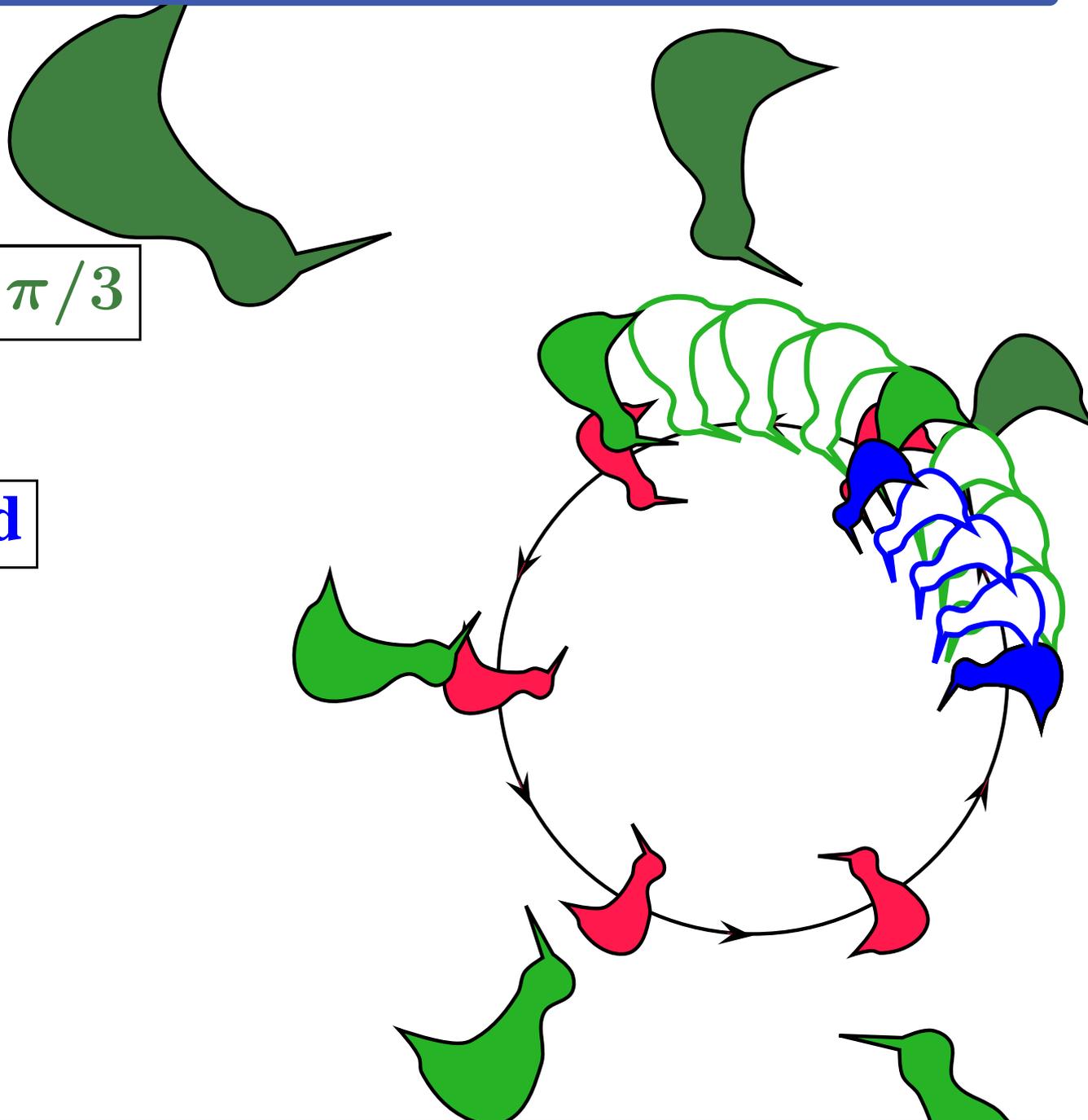
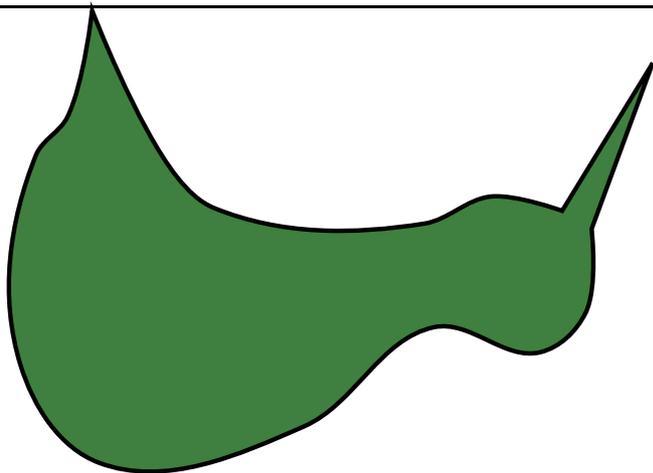
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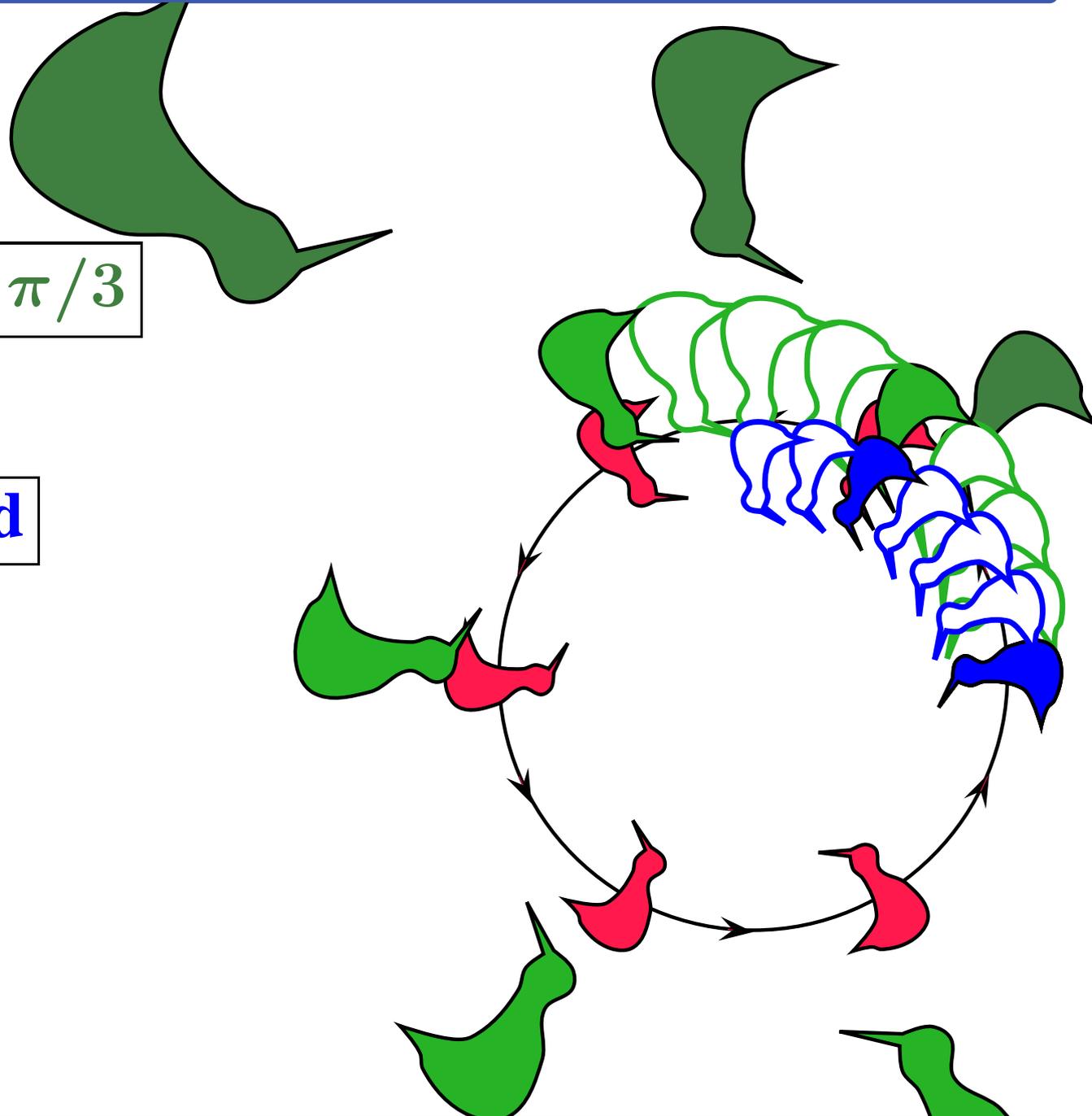
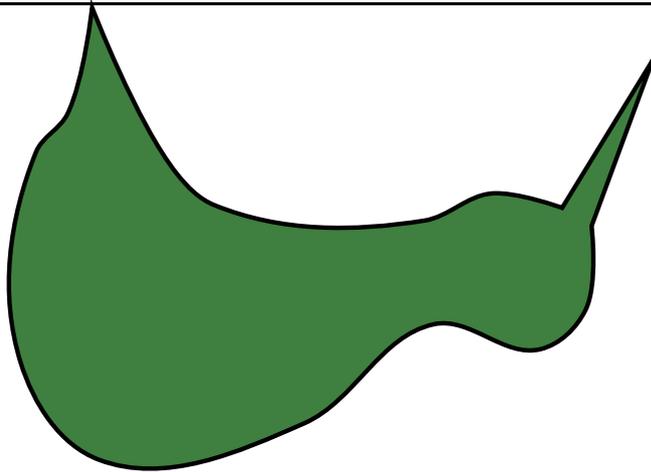
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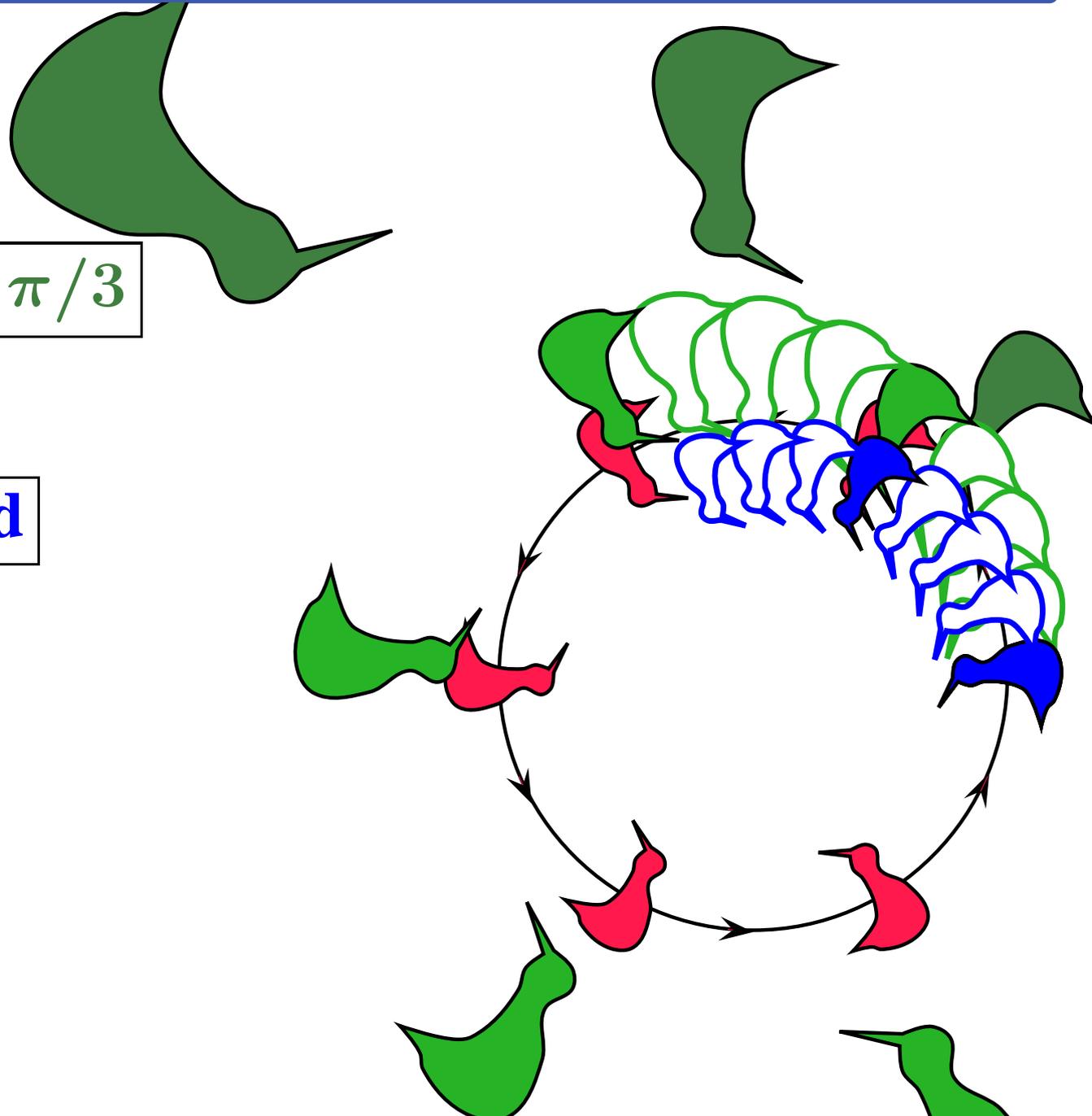
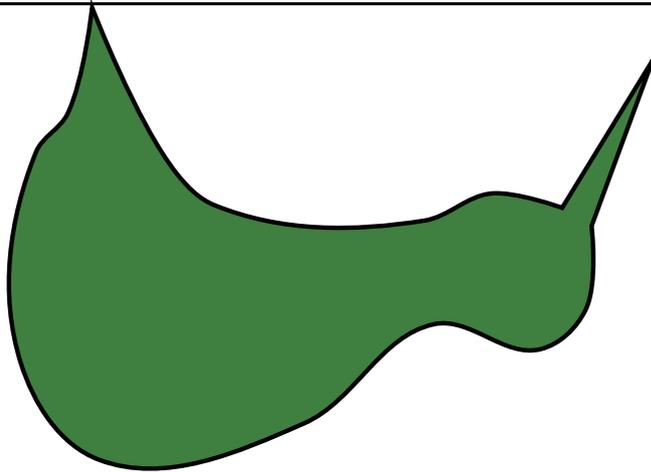
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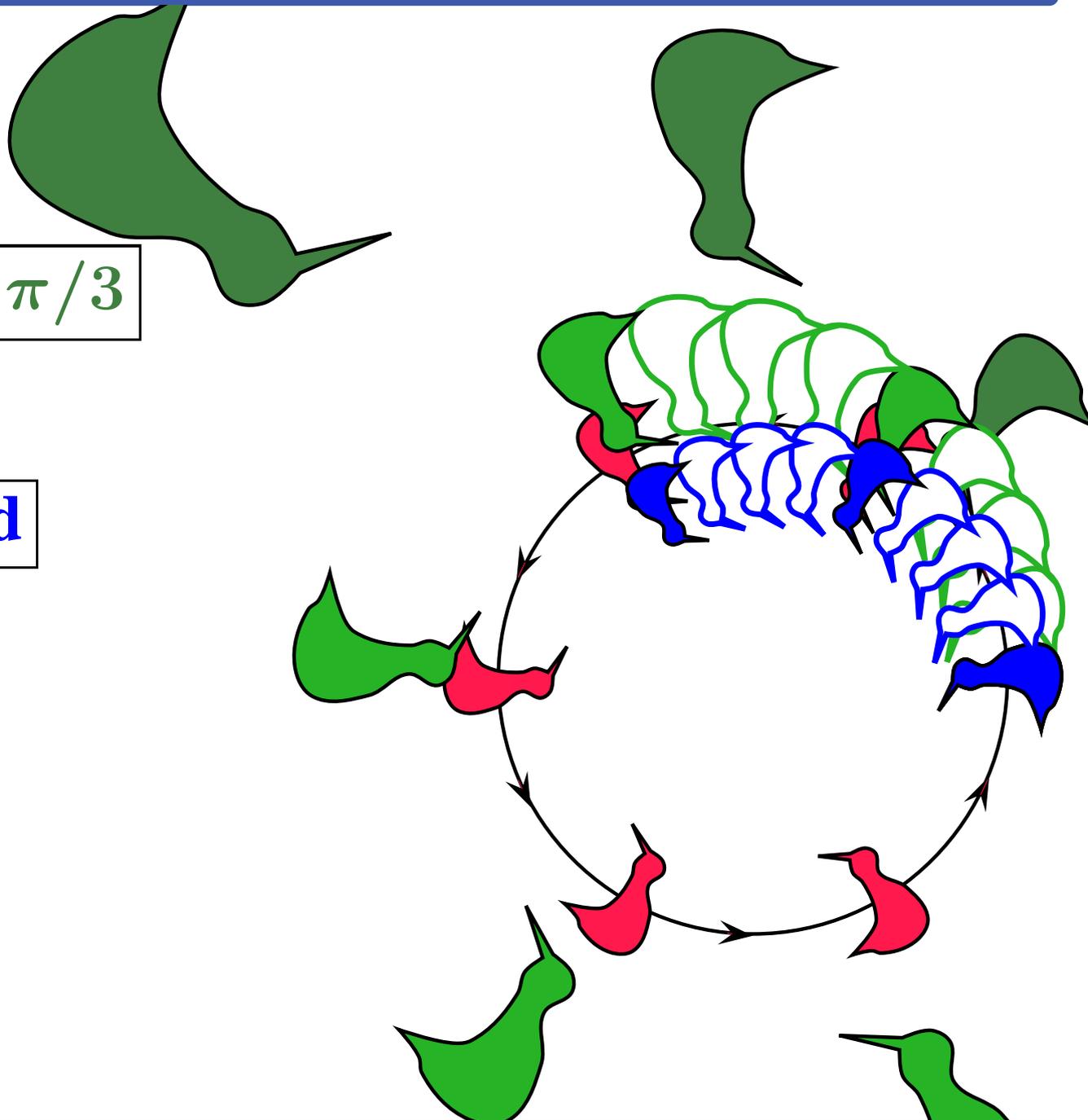
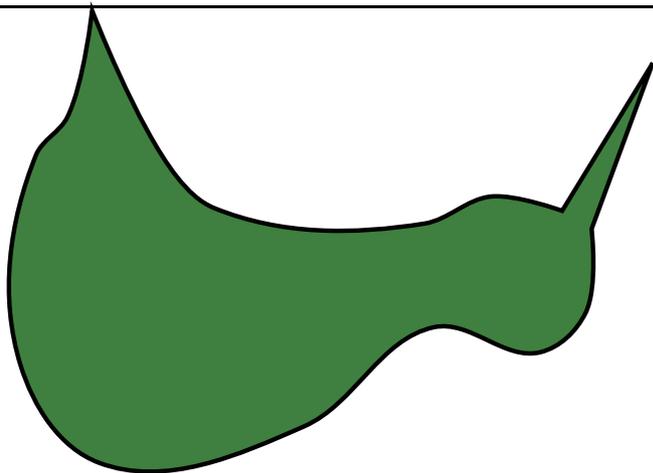
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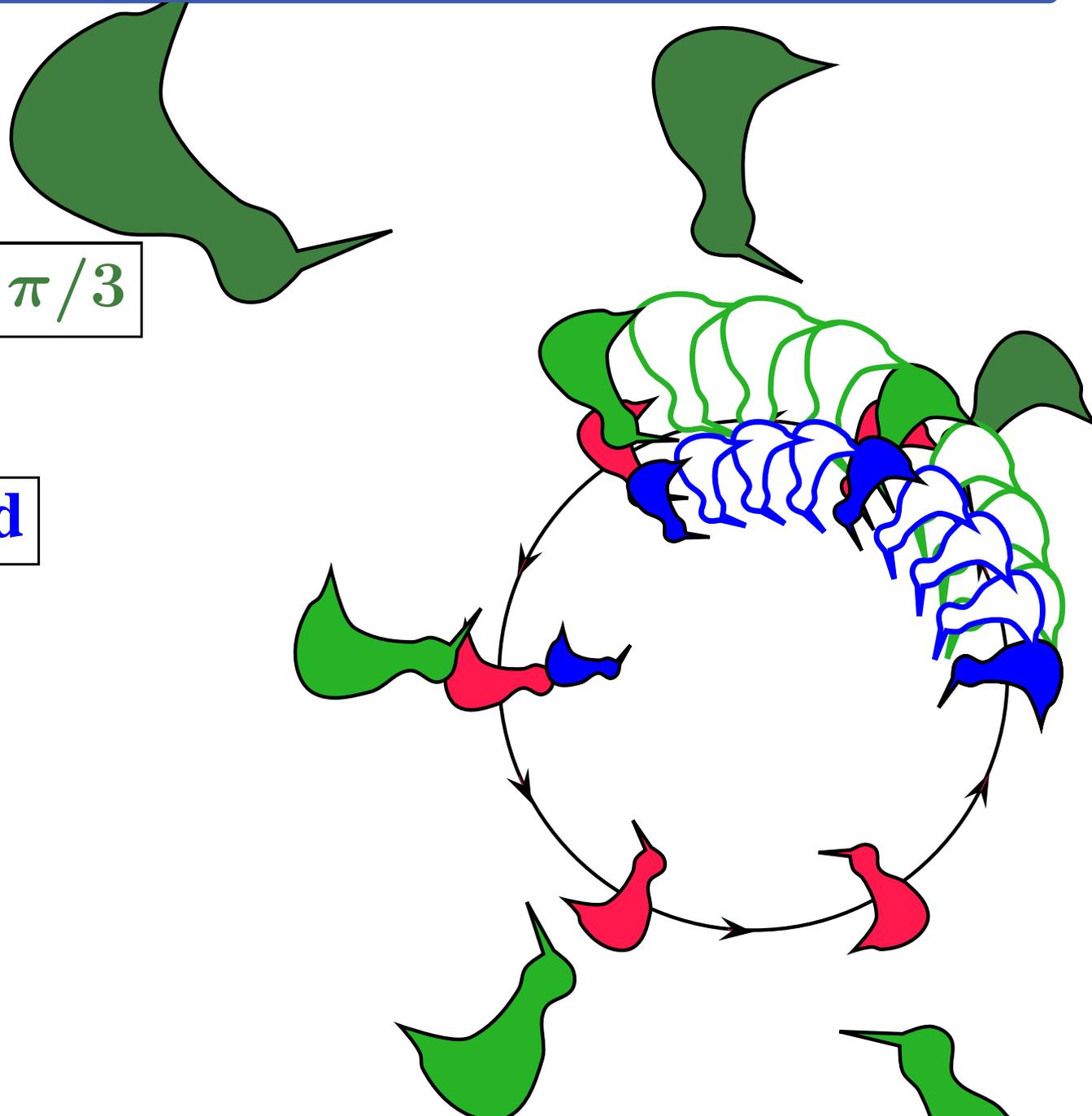
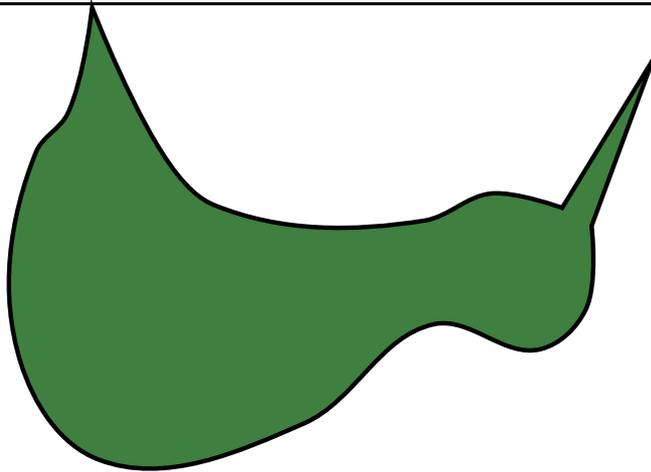
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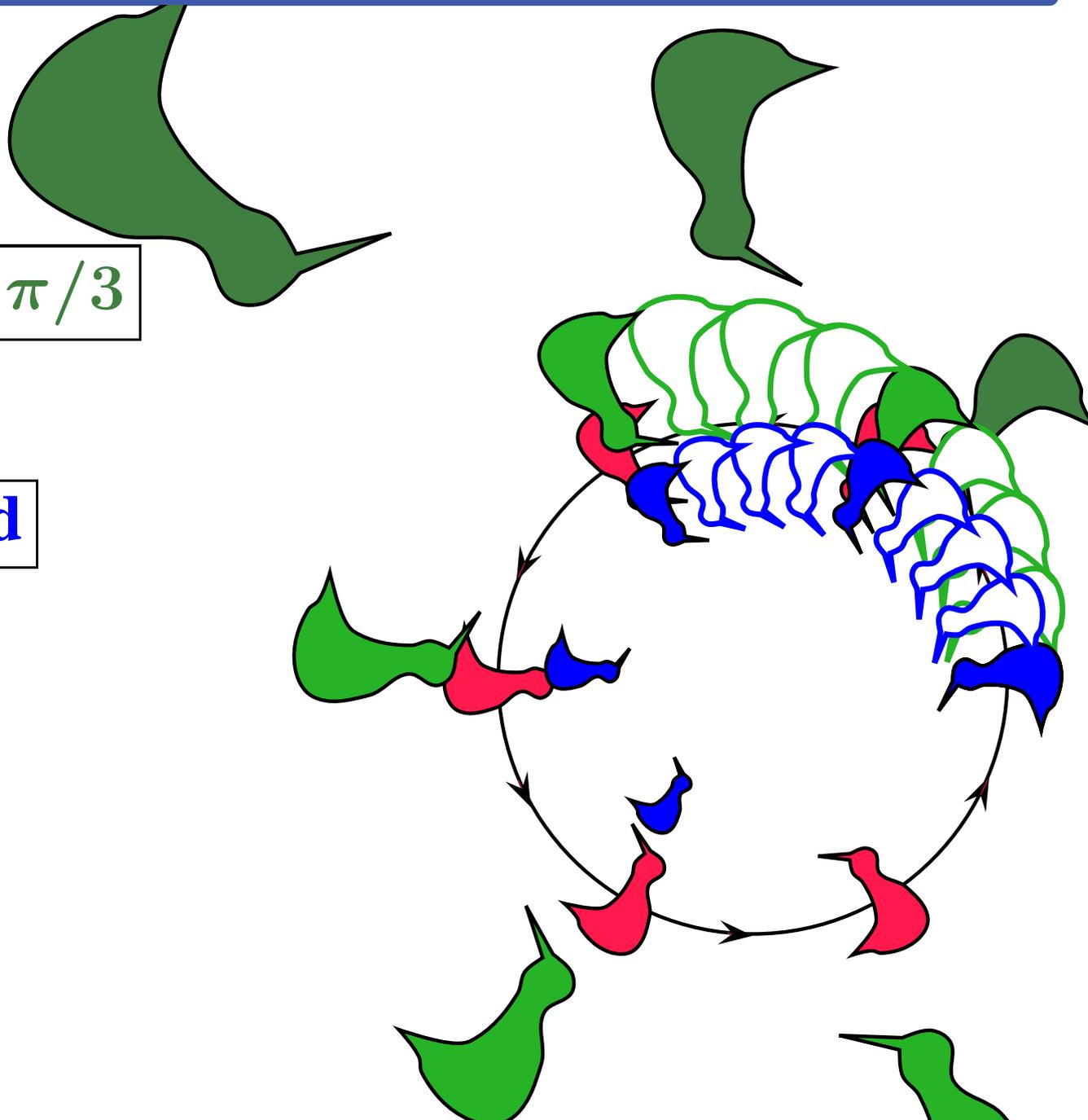
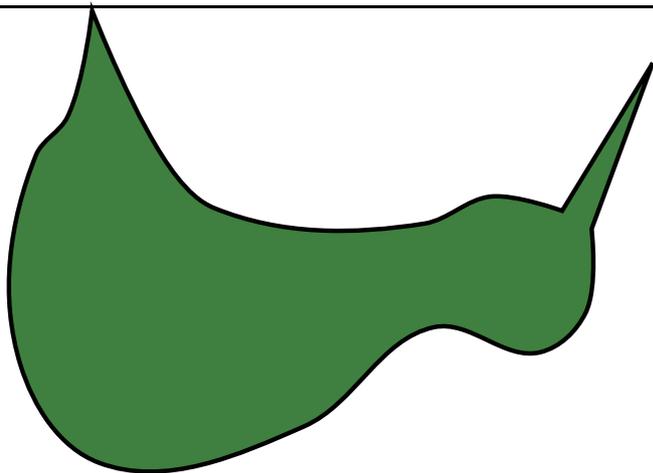
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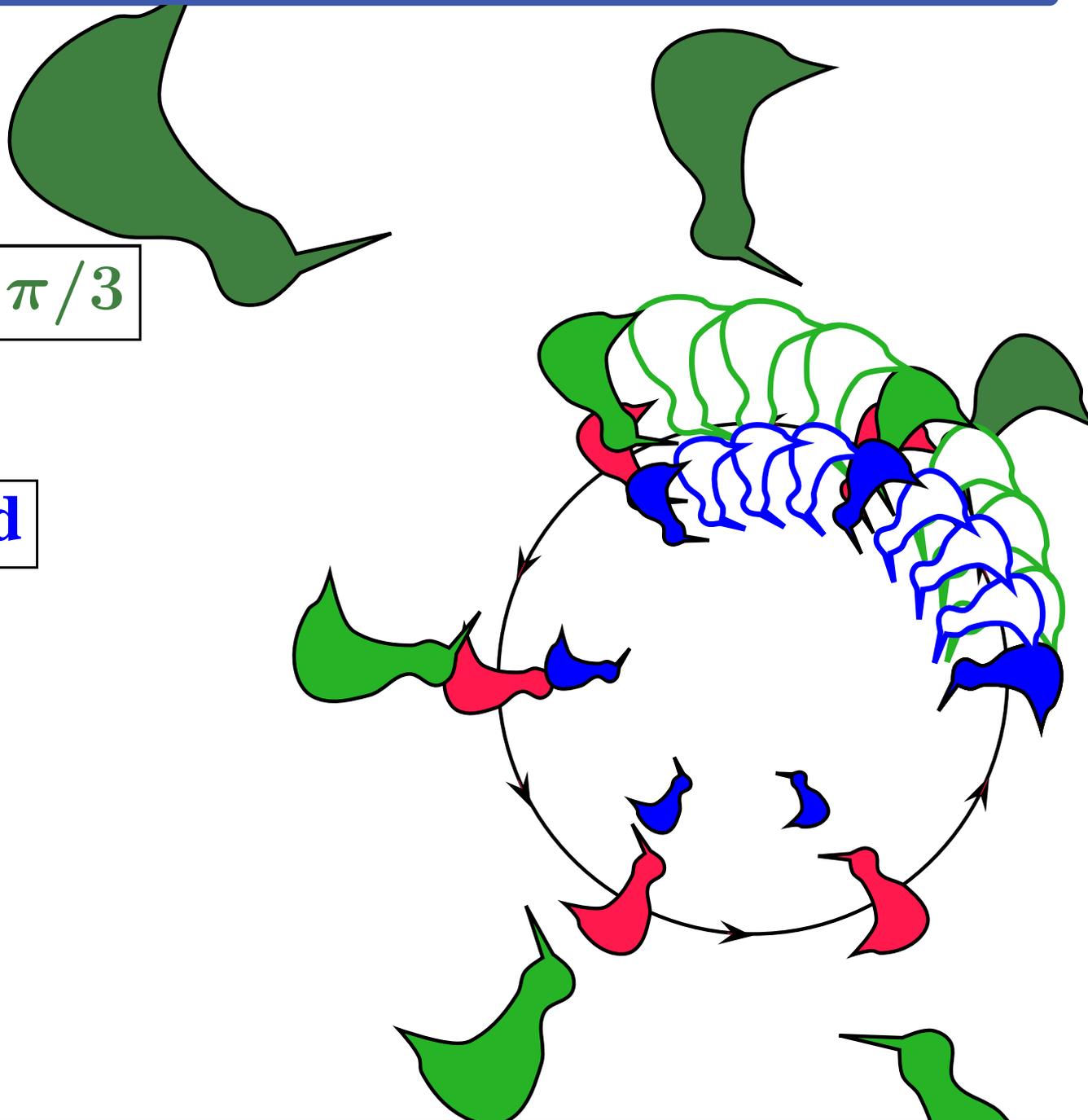
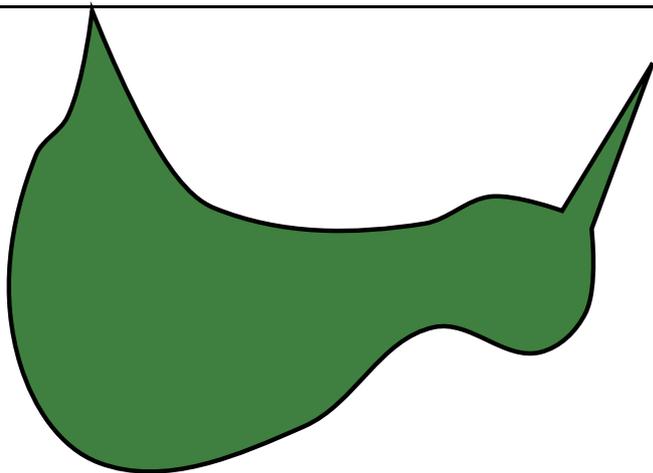
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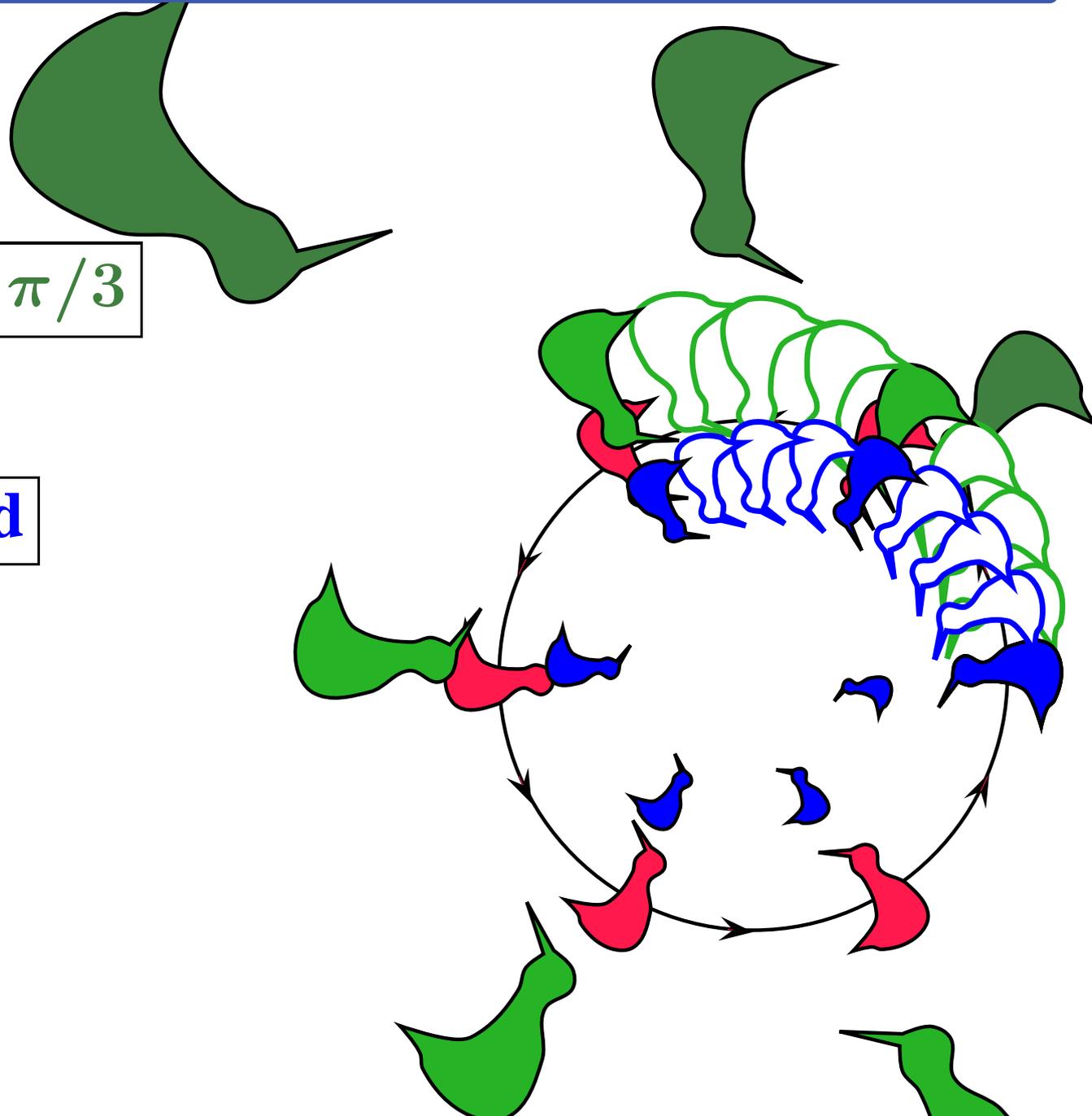
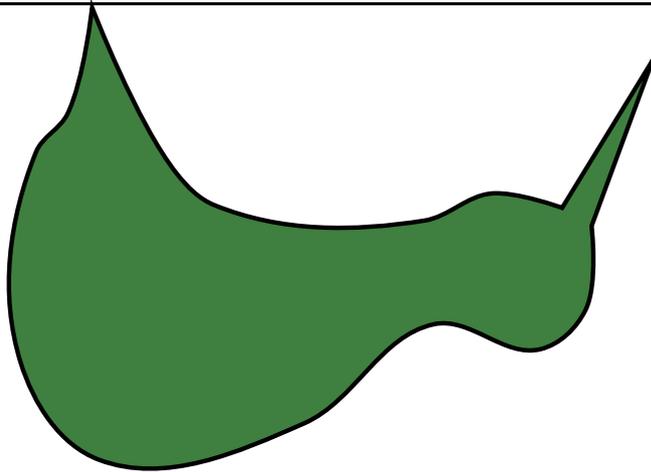
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The differential equation in these computations is an example of a system of the form, based on a “Hamiltonian”  $H(p, q)$ :

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One property of an equation of this form is that  $H(p(t), q(t))$  is invariant, because

$$\dot{H} = \frac{\partial H}{\partial q} \dot{q} + \frac{\partial H}{\partial p} \dot{p} = \frac{\partial H}{\partial q} \frac{\partial H}{\partial p} - \frac{\partial H}{\partial p} \frac{\partial H}{\partial q} = 0.$$

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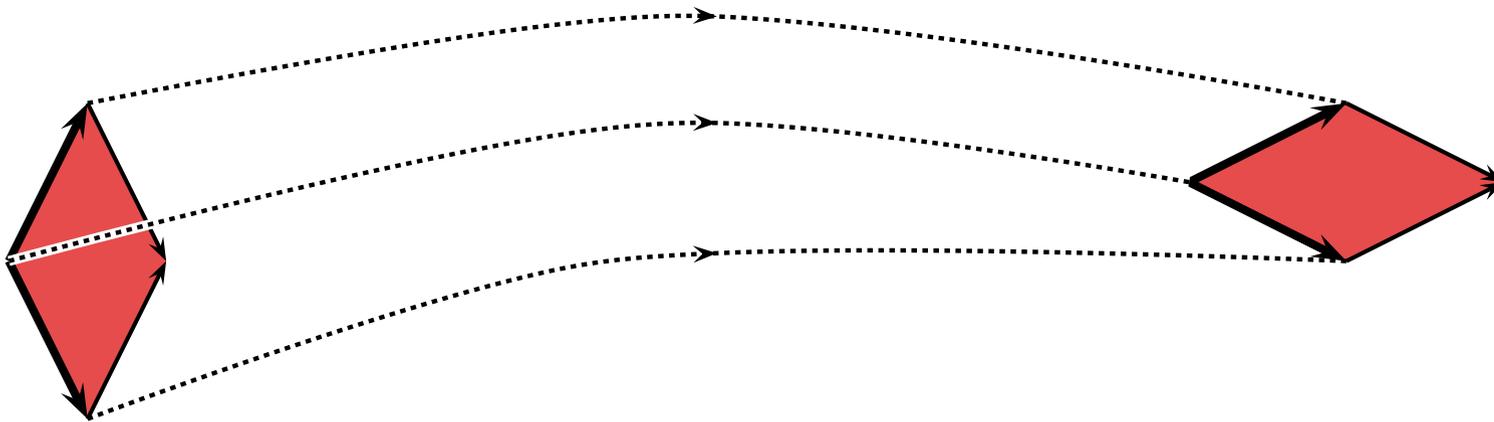
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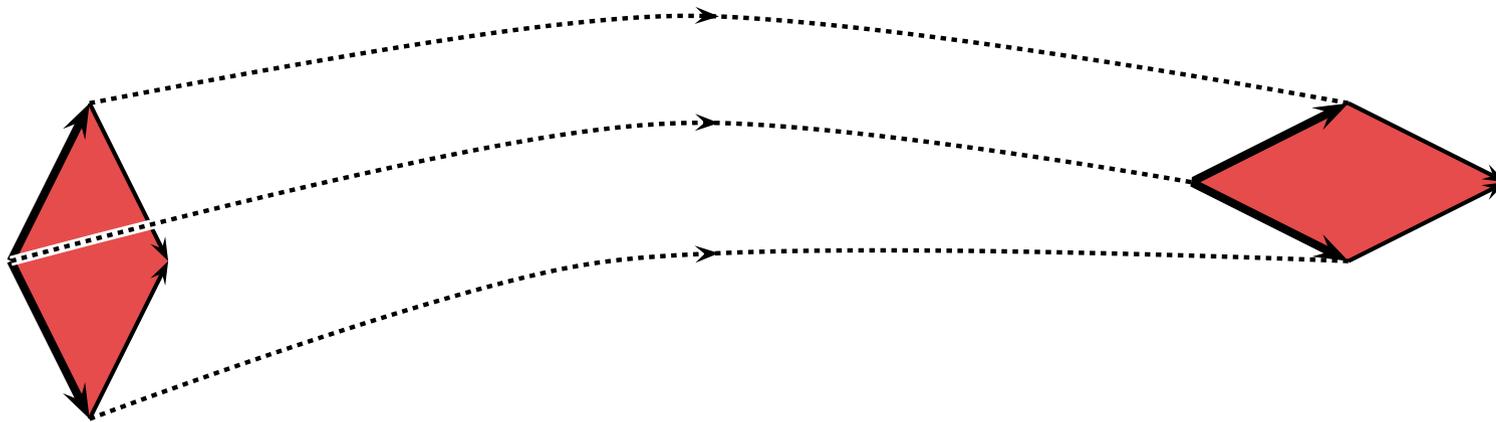


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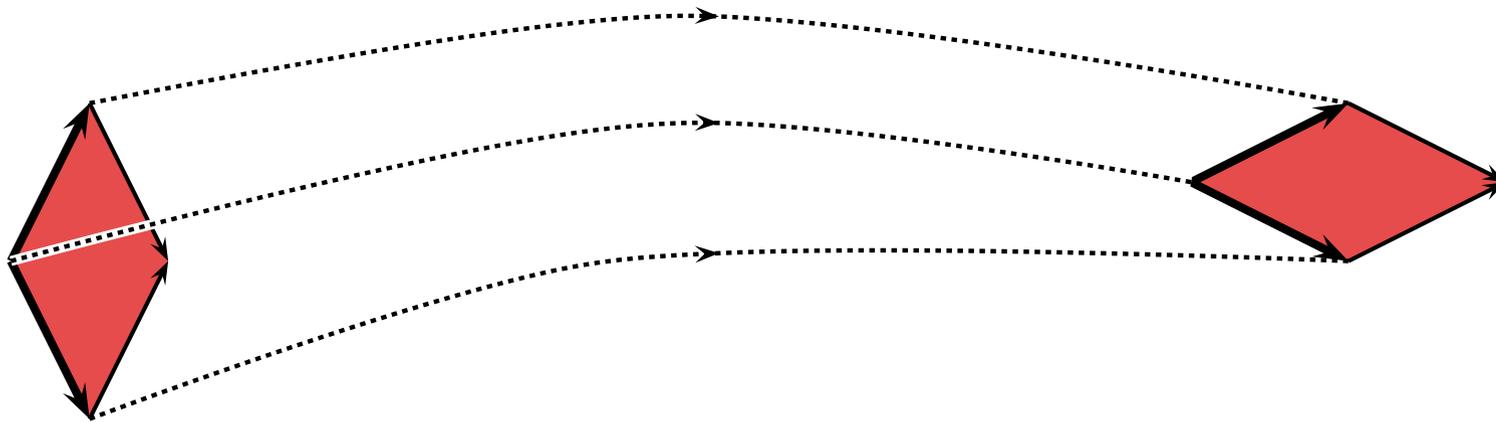
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The reason for this hinges on a well-known fact.

**Well-known fact 1** *Let  $X$  denote a matrix-valued function of  $t$  which satisfies the differential equation*

$$\dot{X}(t) = M(t)X(t),$$

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**Proof.** Let  $\Xi(t)$  denote the adjoint matrix of  $X(t)$  and write the columns of  $X$  as  $x_i$  and the rows of  $\Xi$  as  $\xi_i^T$ .

We have

$$\begin{aligned}\dot{D} &= \sum_{i=1}^n \xi_i^T \dot{x}_i = \sum_{i=1}^n \xi_i^T M x_i \\ &= \text{tr}(\Xi M X) = \text{tr}(M X \Xi) \\ &= \text{tr}(M)D.\end{aligned}$$

**Theorem 2** *Let  $X(t)$  denote the matrix*

$$X(t) = \begin{bmatrix} dp_1(t) & dp_2(t) \\ dq_1(t) & dq_2(t) \end{bmatrix},$$

*where  $(p + dp_1, q + dq_1)$  and  $(p + dp_2, q + dq_2)$  are solutions to*

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**Proof.** Taking account of Well-Known Fact 1, we need only to prove that the trace of the Jacobian matrix is zero.

The Jacobian matrix is

$$\begin{bmatrix} -\frac{\partial^2 H}{\partial p \partial q} & -\frac{\partial^2 H}{\partial q^2} \\ \frac{\partial^2 H}{\partial p^2} & \frac{\partial^2 H}{\partial q \partial p} \end{bmatrix},$$

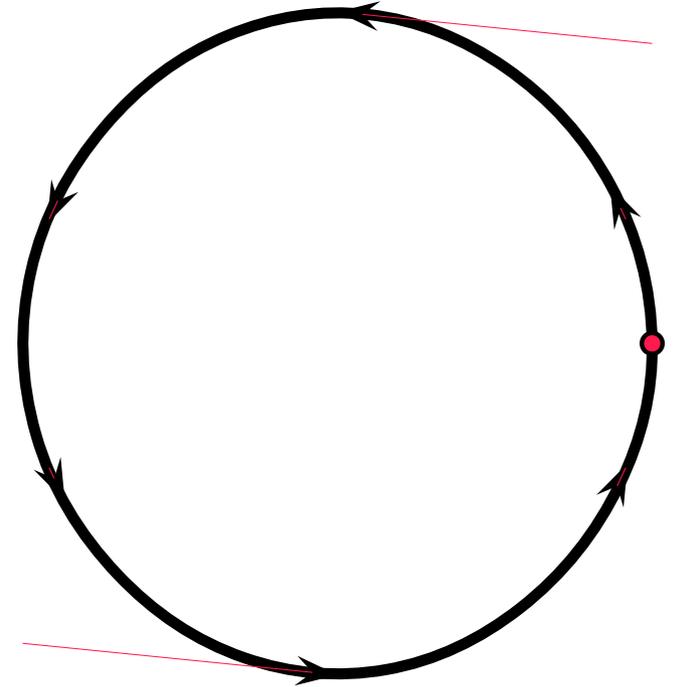
which does indeed have zero trace.

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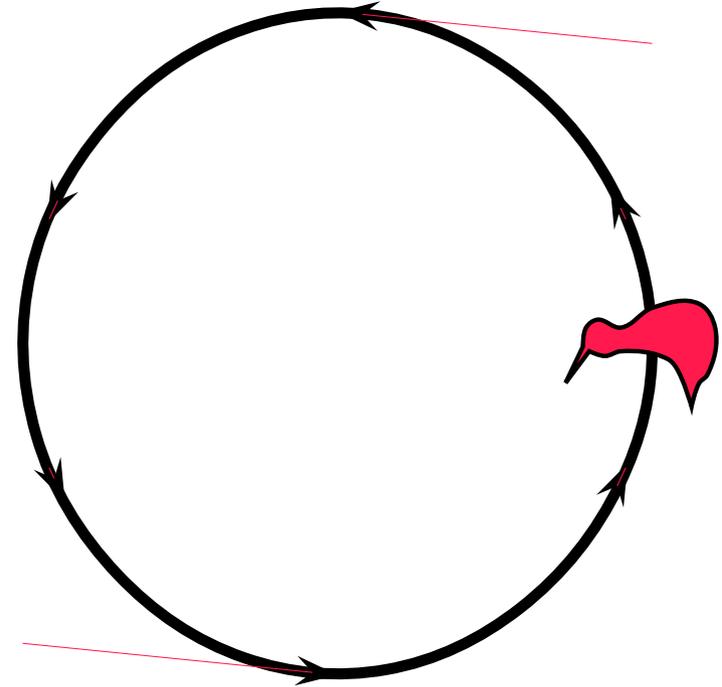
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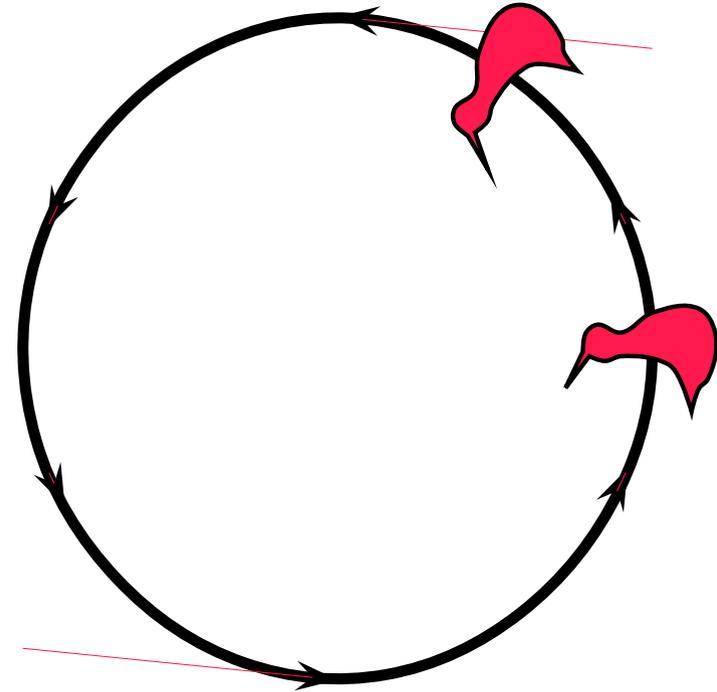
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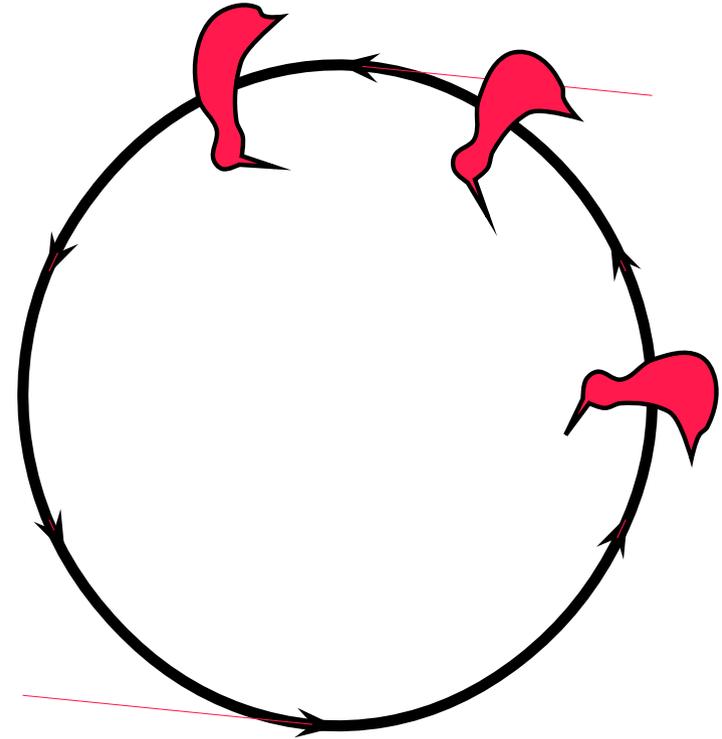
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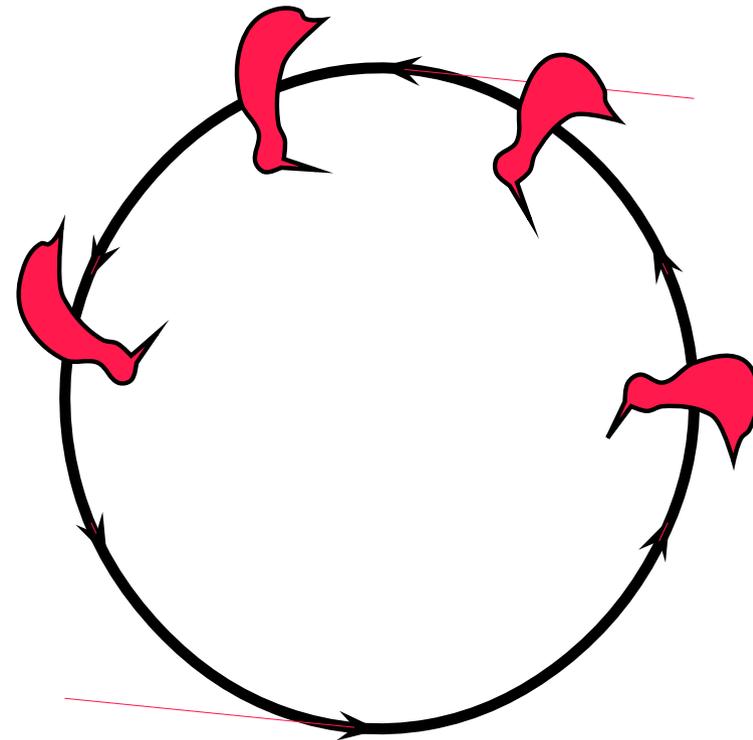
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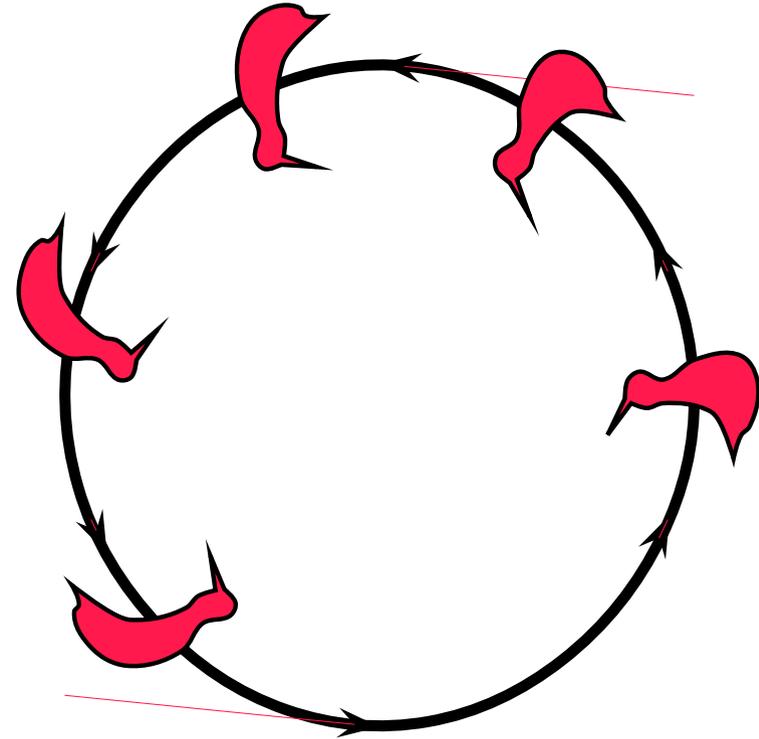
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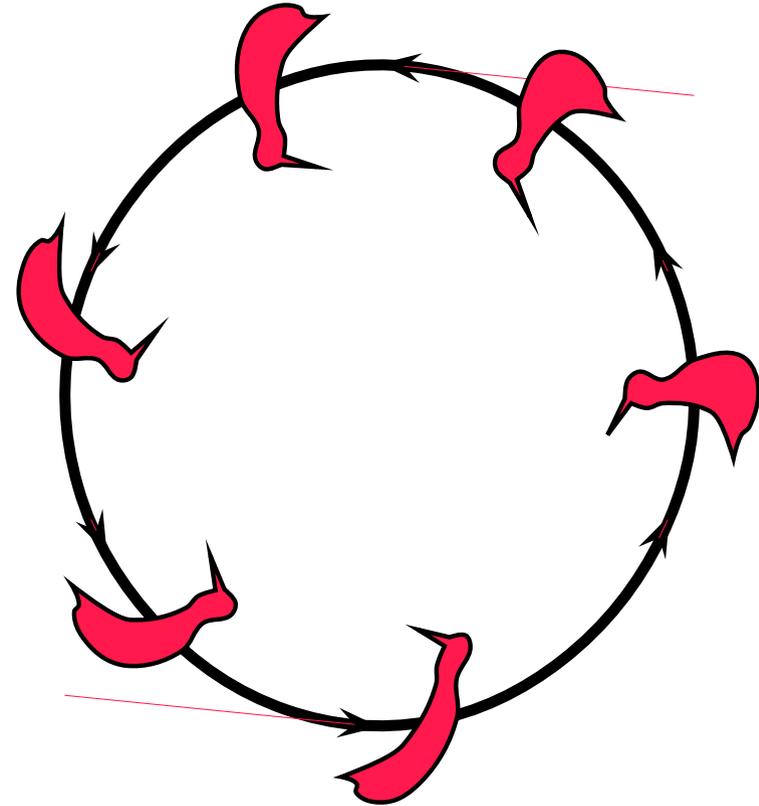
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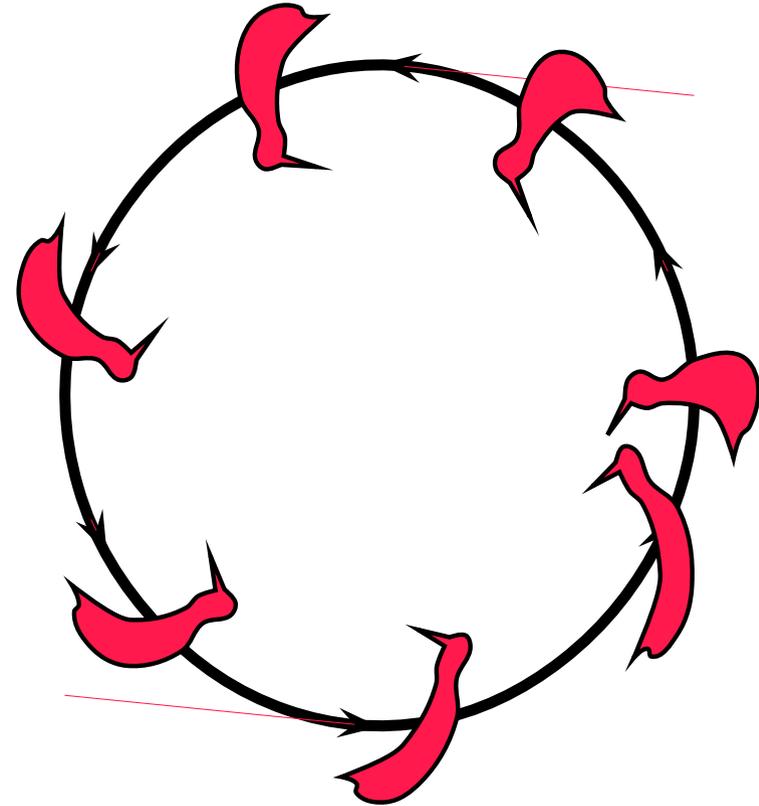
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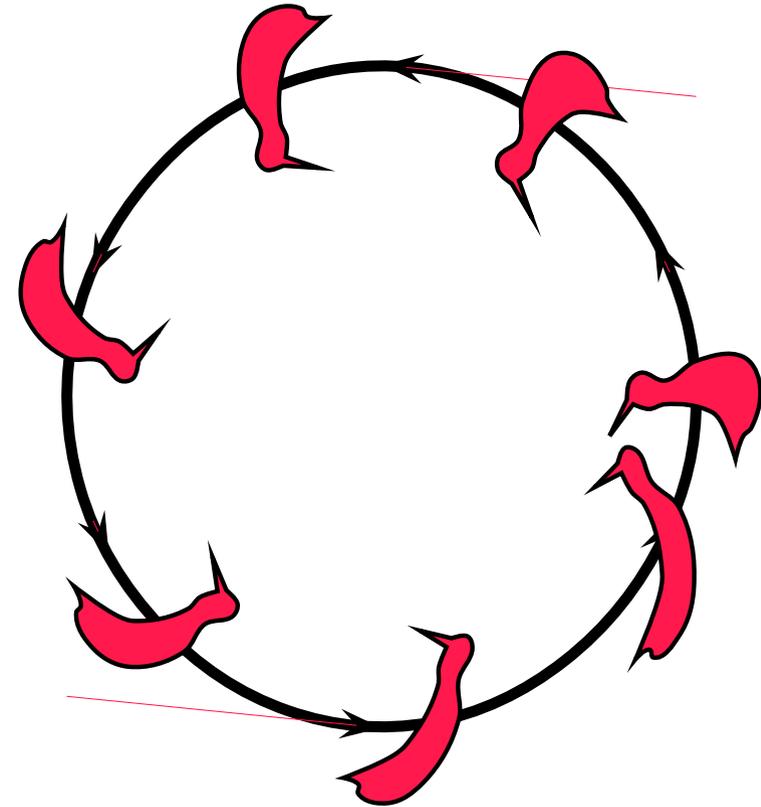


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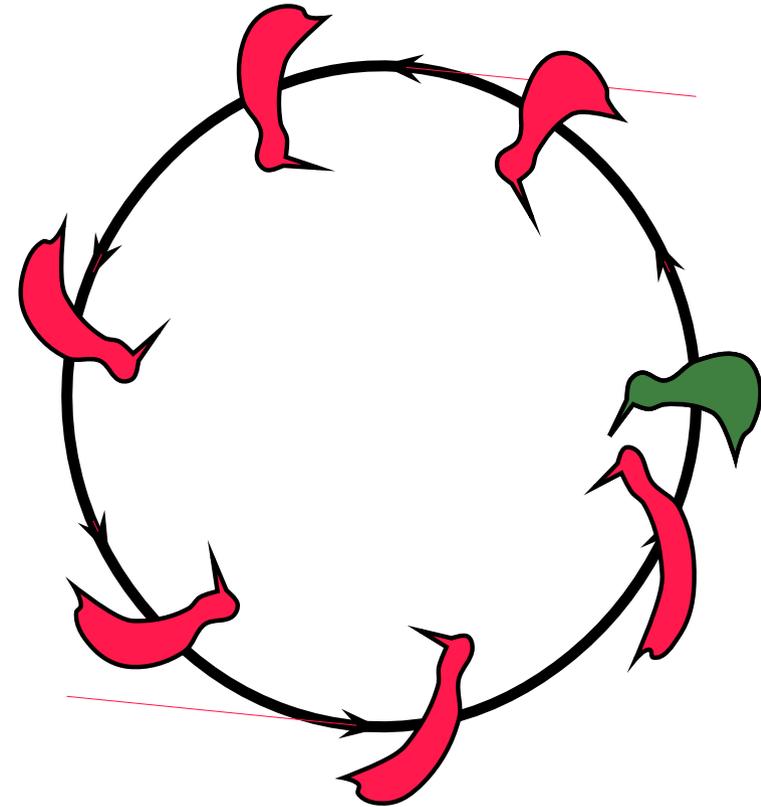


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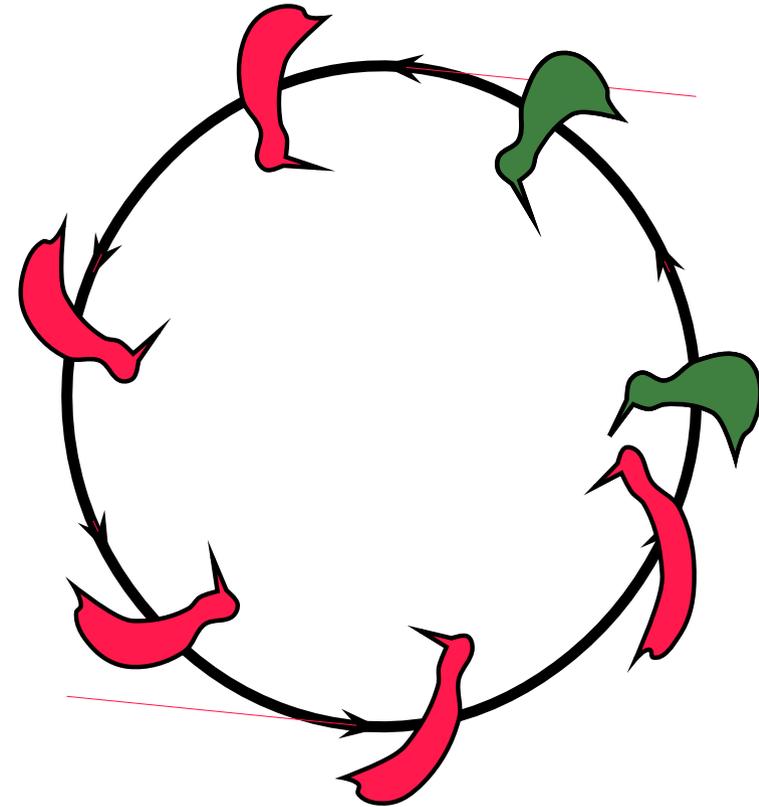


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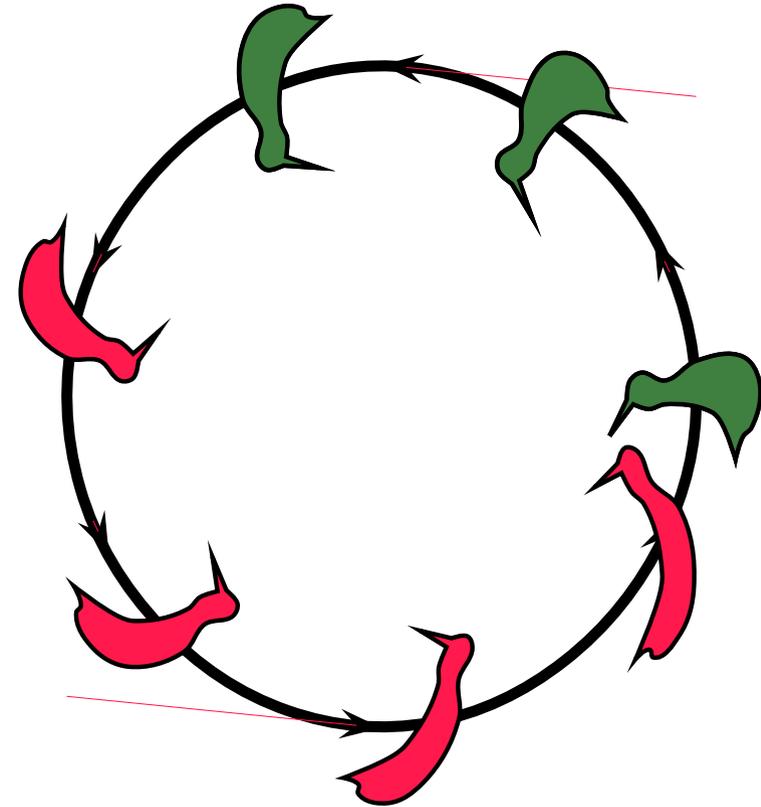


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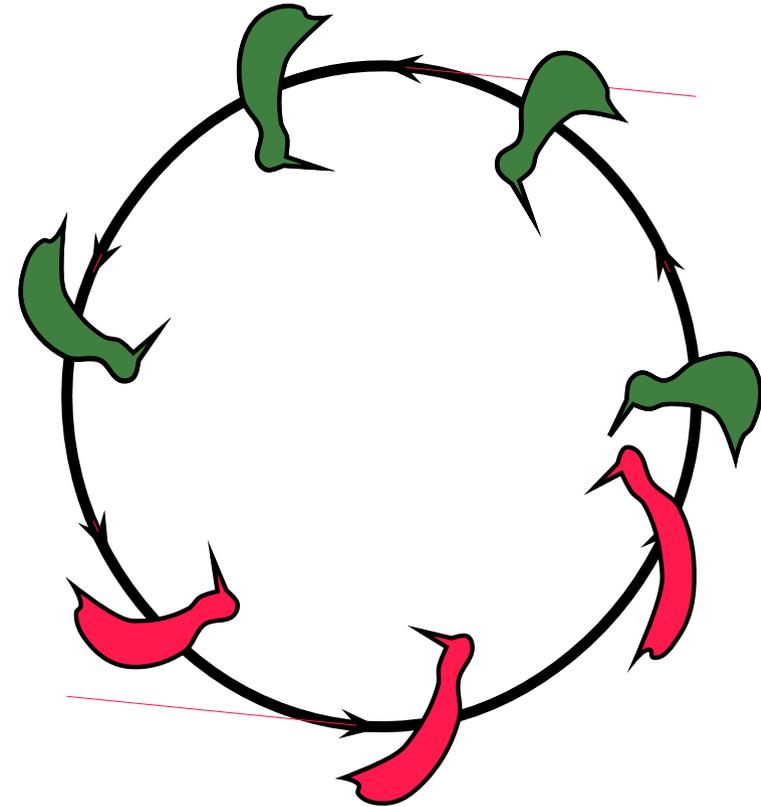


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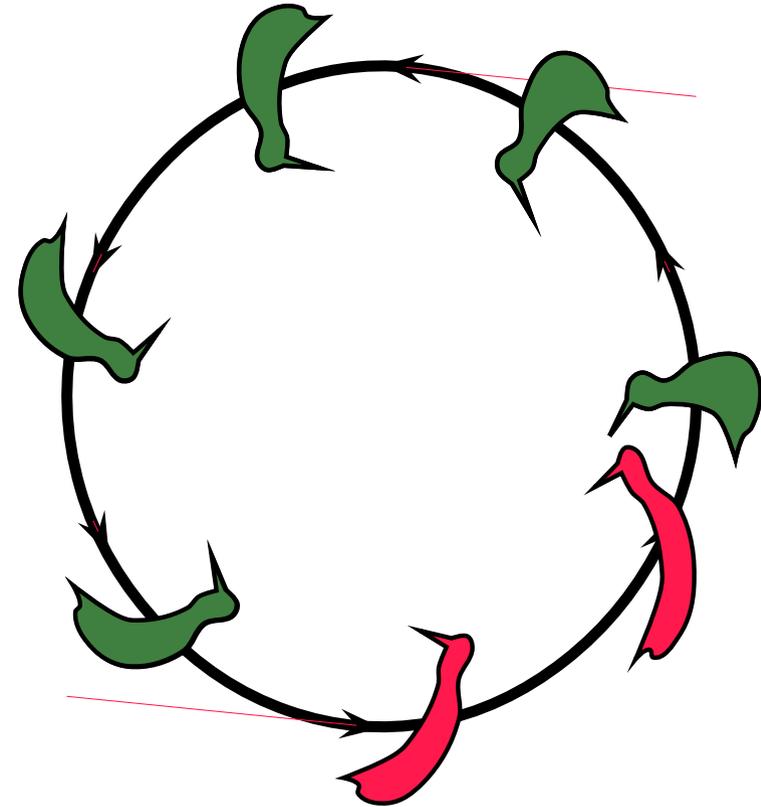


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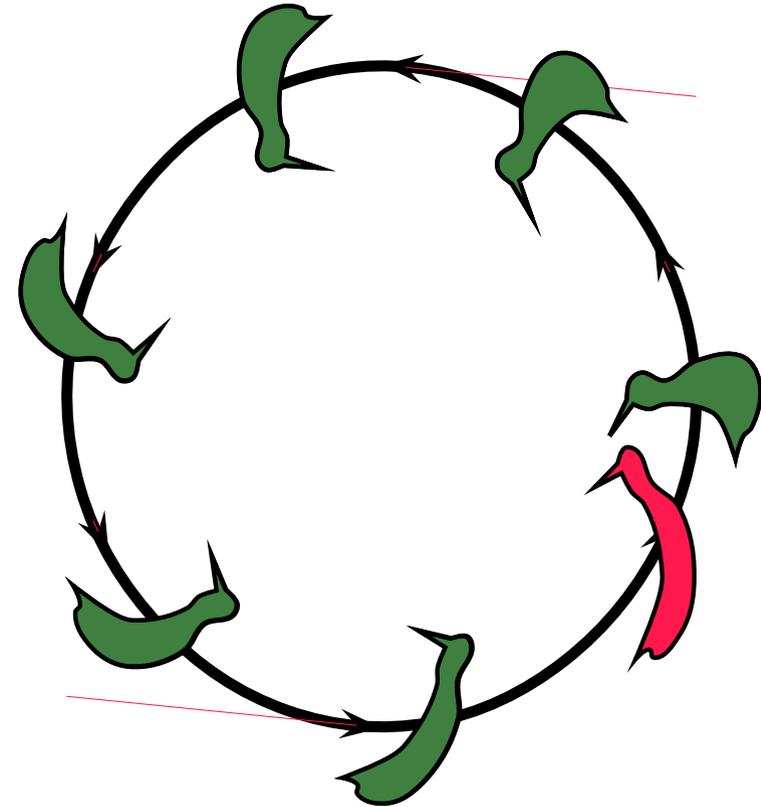


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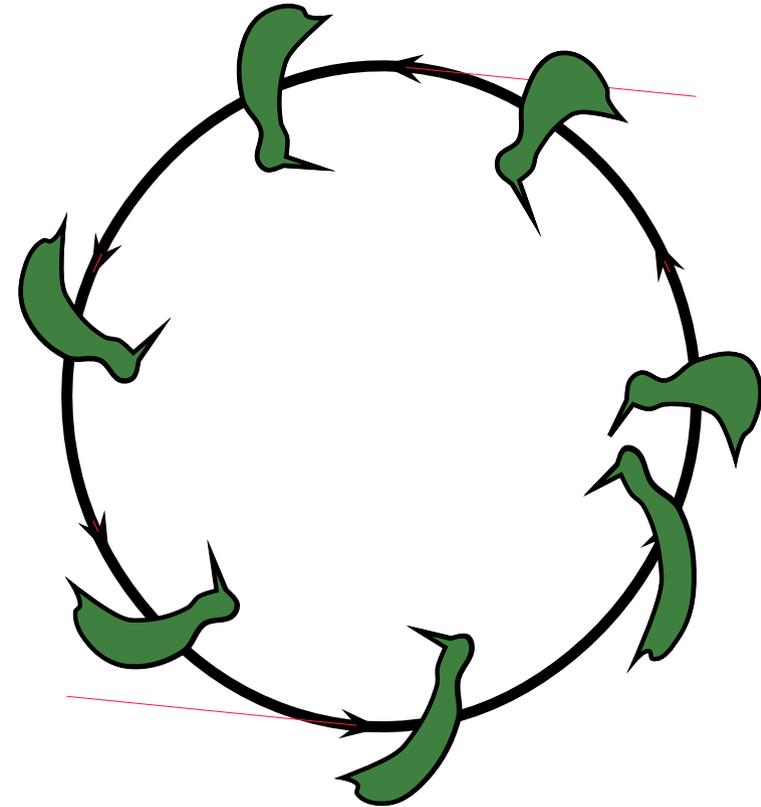


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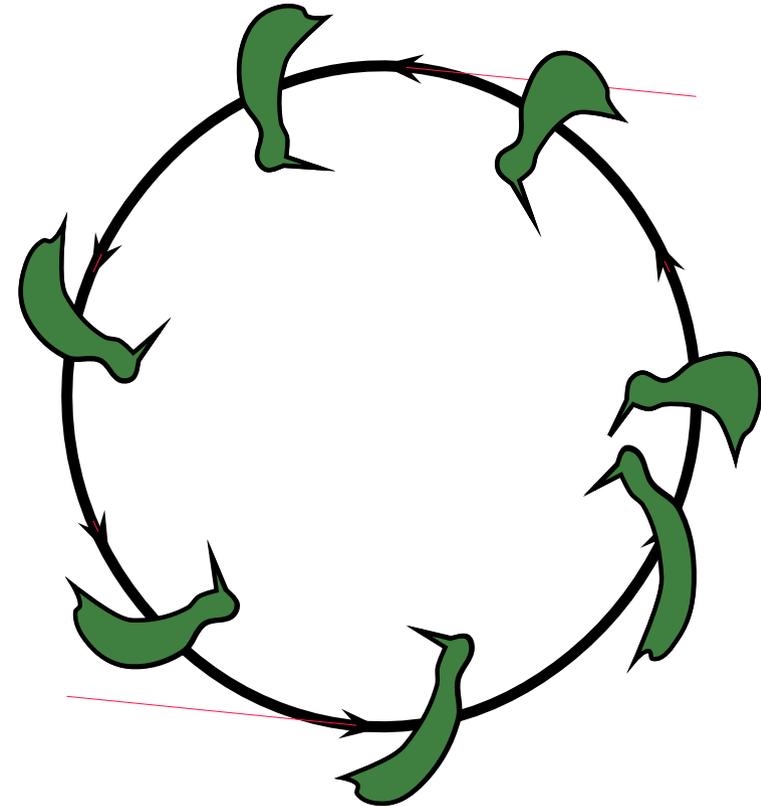
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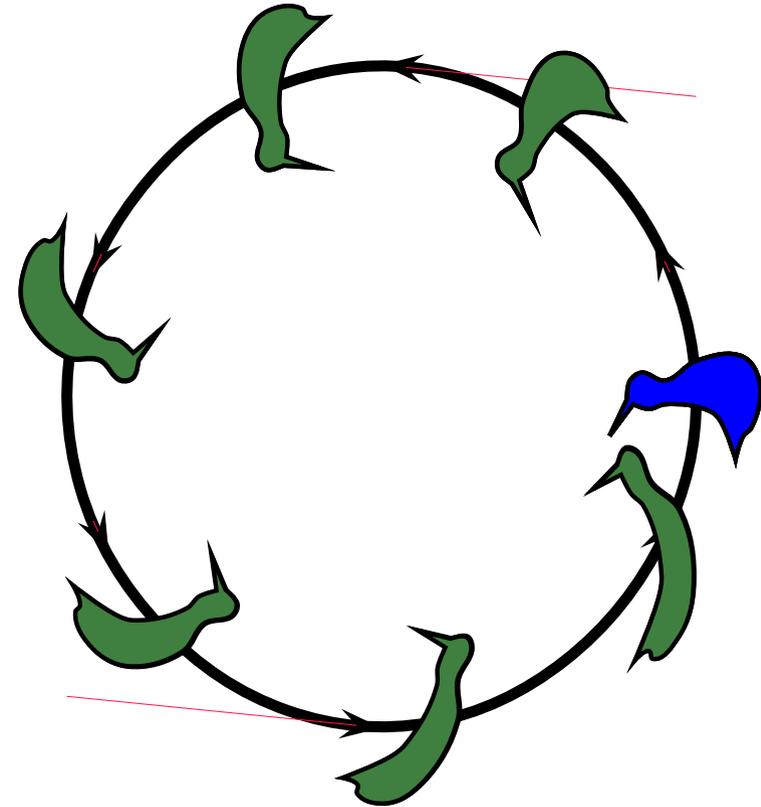
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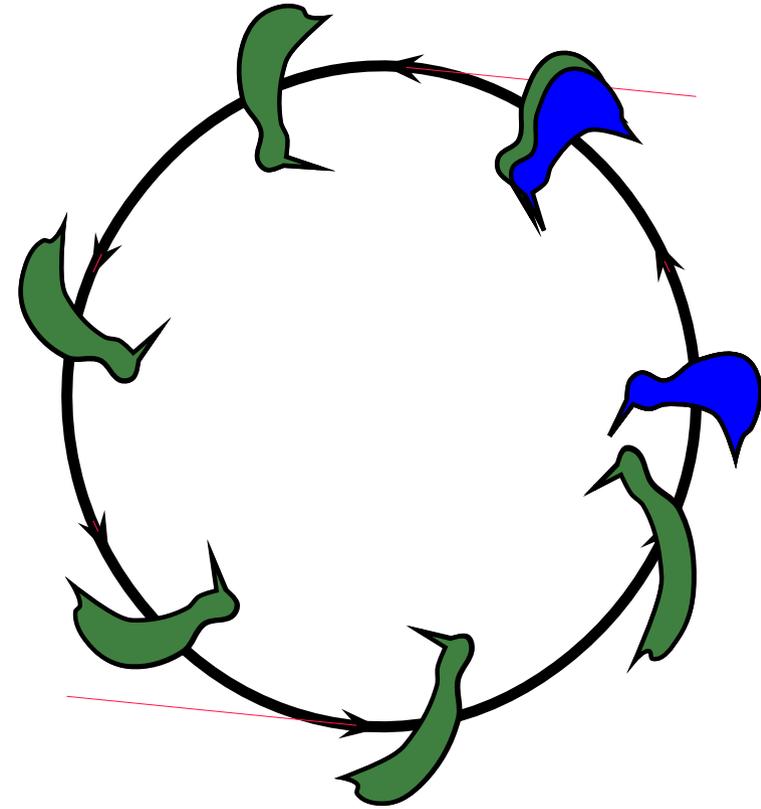
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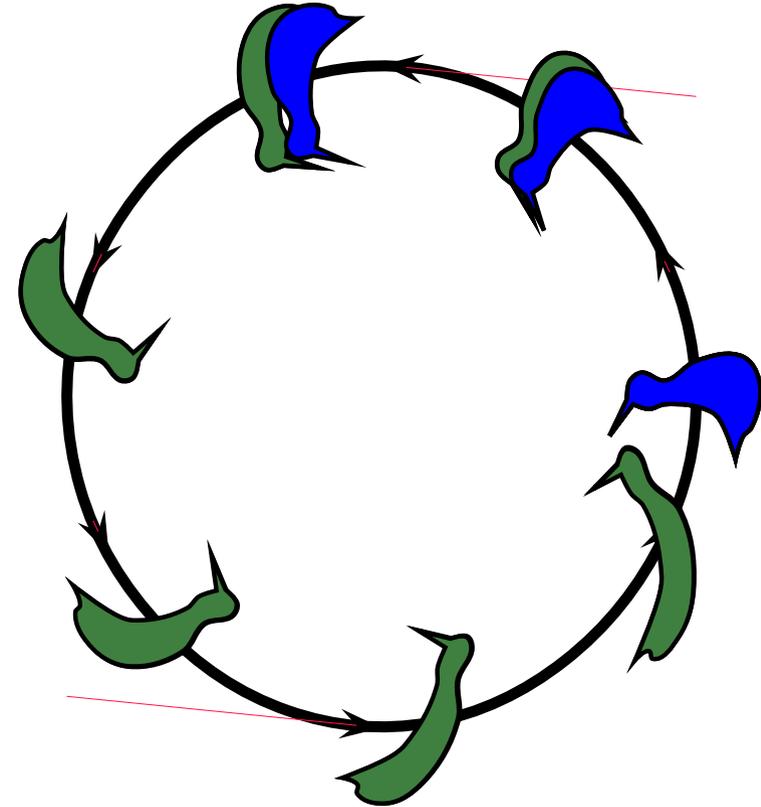
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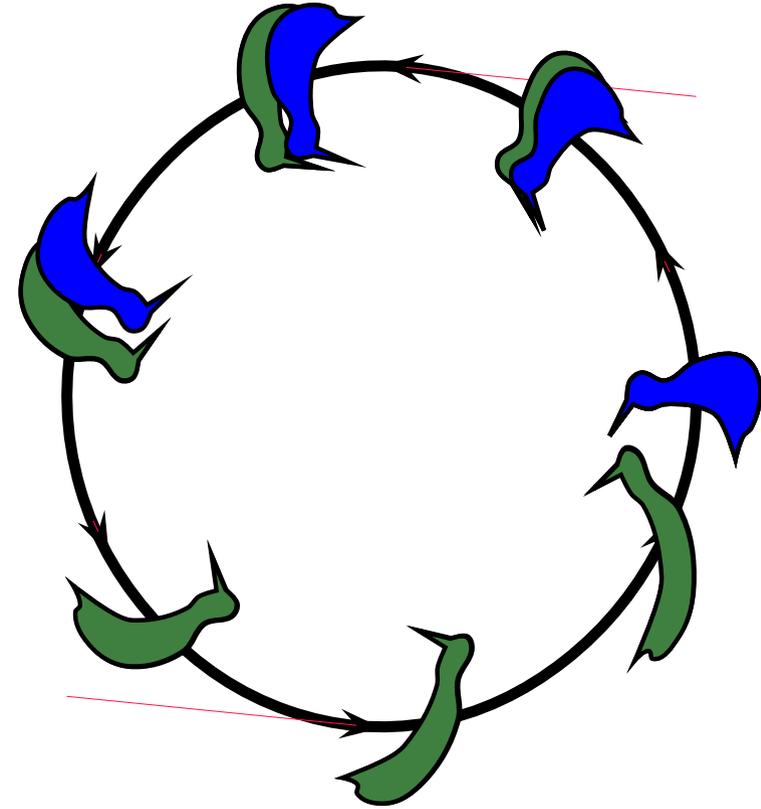
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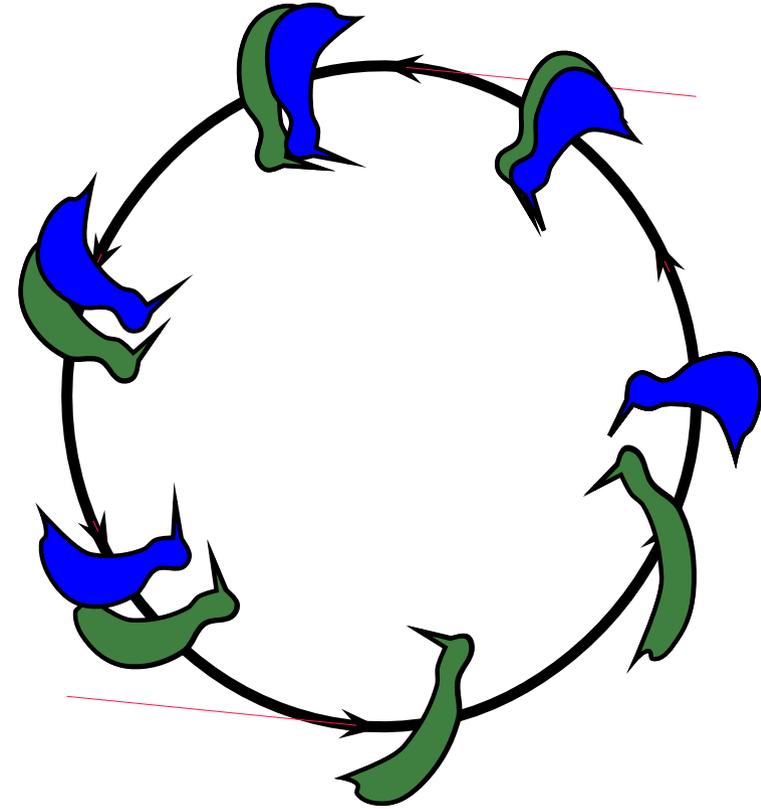
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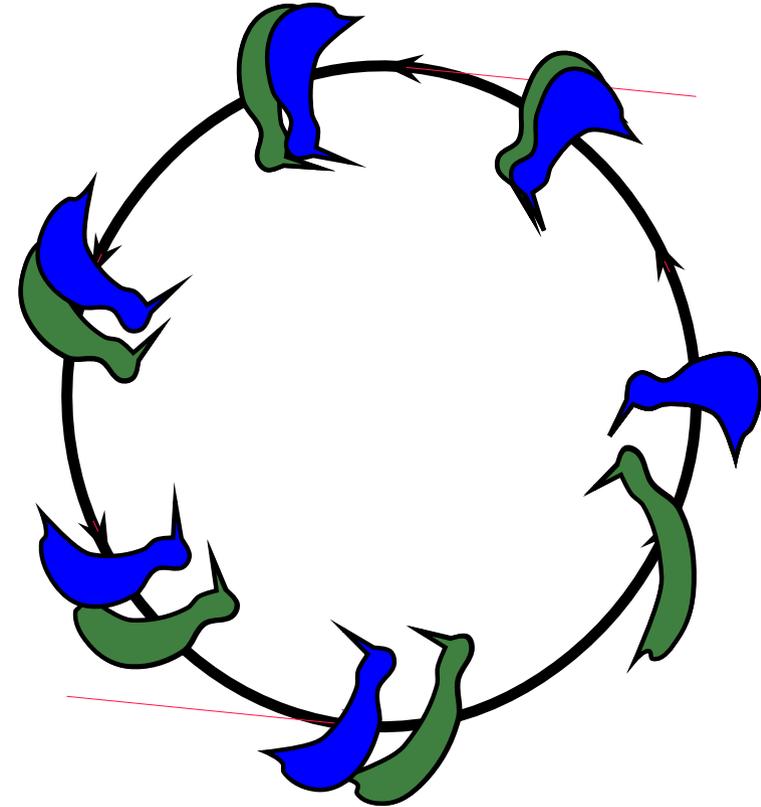
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Gauss method

$\frac{3-\sqrt{3}}{6}$	$\frac{3-2\sqrt{3}}{12}$	$\frac{1}{4}$
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Mid-point rule

$\frac{1}{2}$	$\frac{1}{2}$	$\frac{1}{2}$
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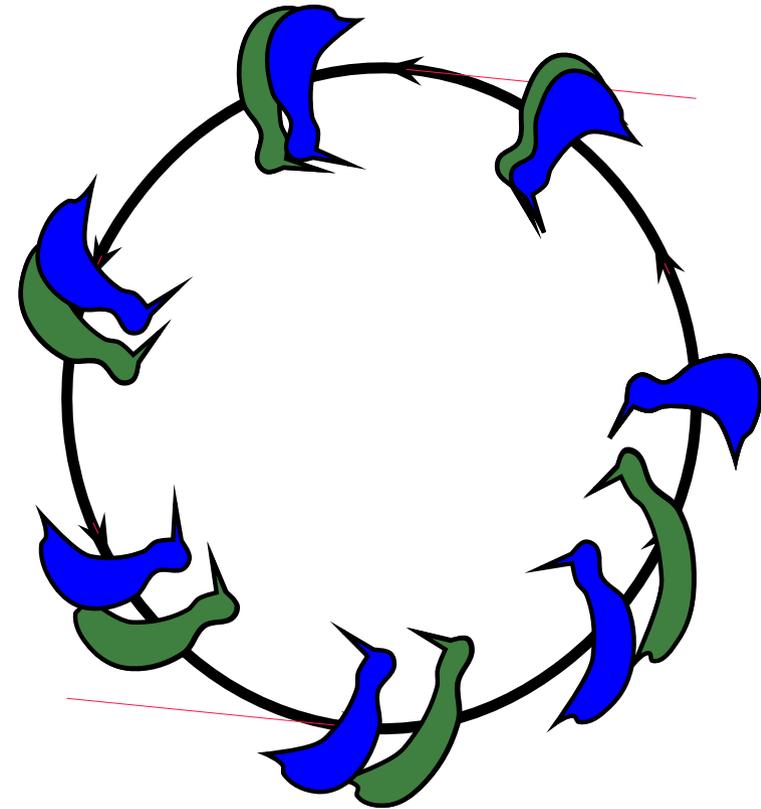
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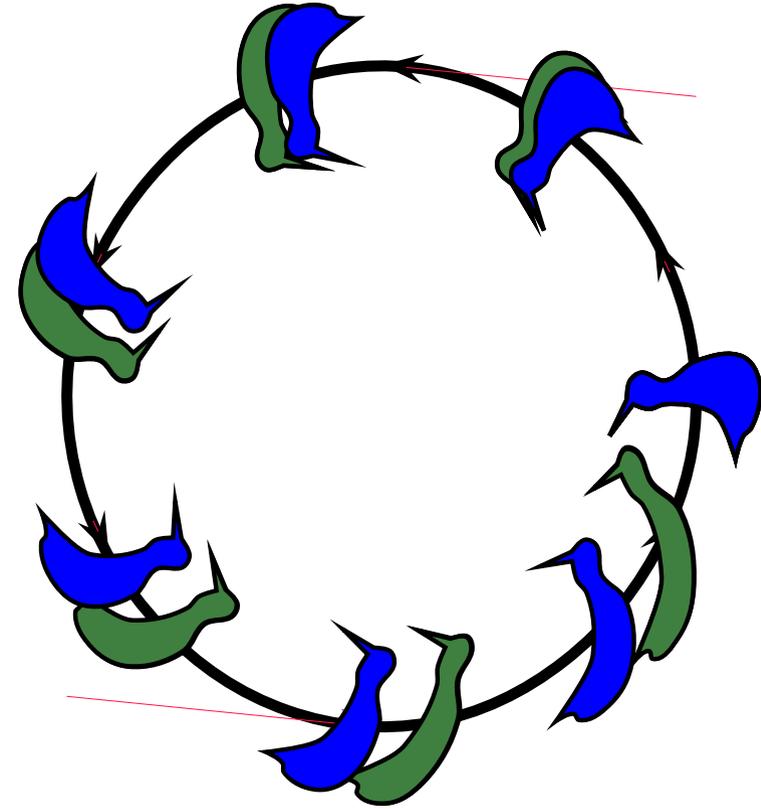
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$\frac{1}{2}$	$\frac{1}{2}$	$\frac{1}{2}$
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**General linear method**

$\frac{3+\sqrt{3}}{6}$	$0$	$1$	$\frac{-3-2\sqrt{3}}{3}$
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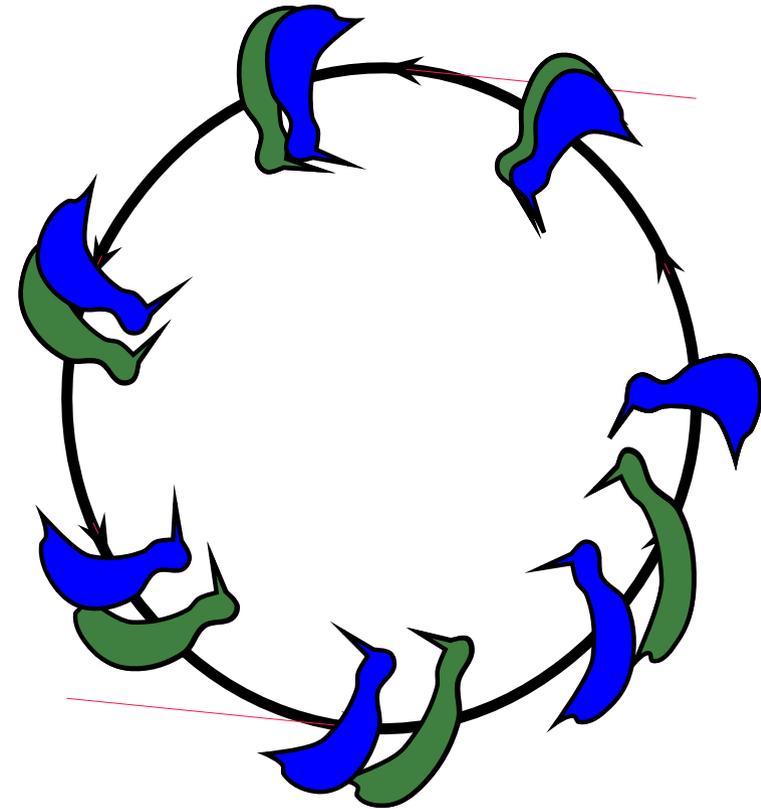
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# Experiments with some symplectic methods

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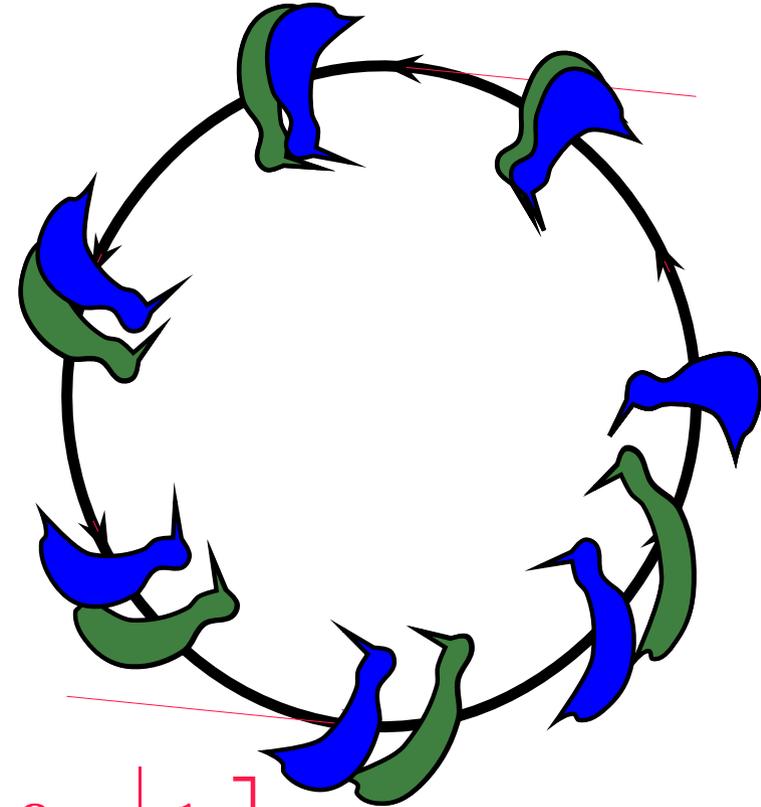
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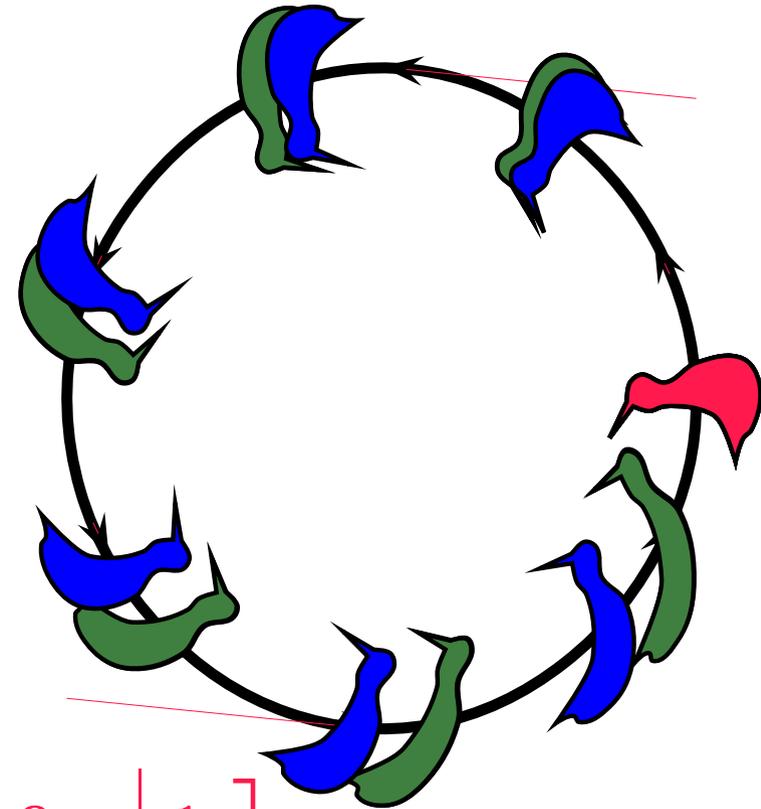
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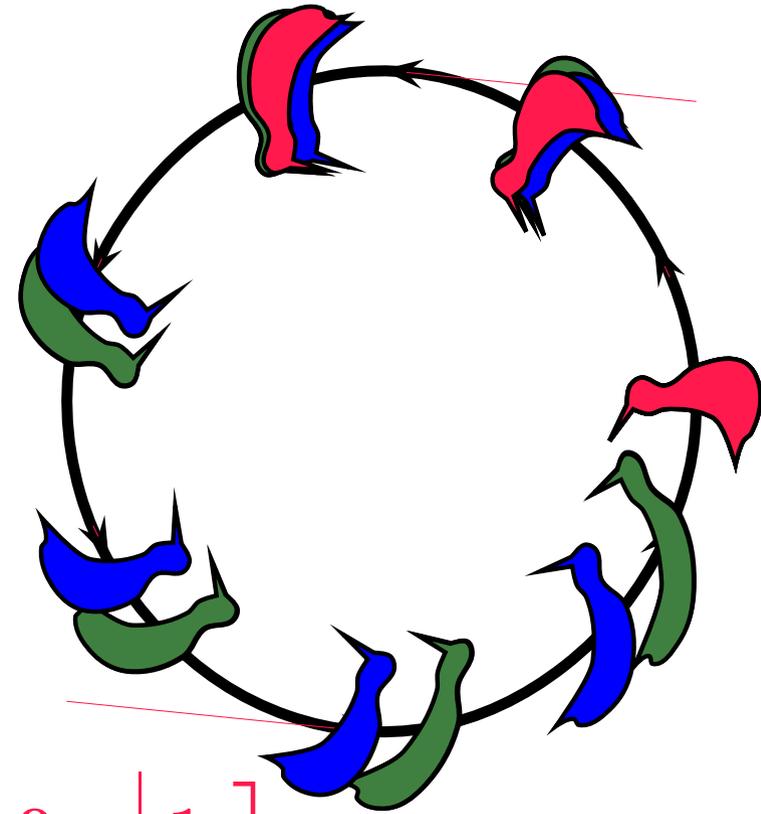
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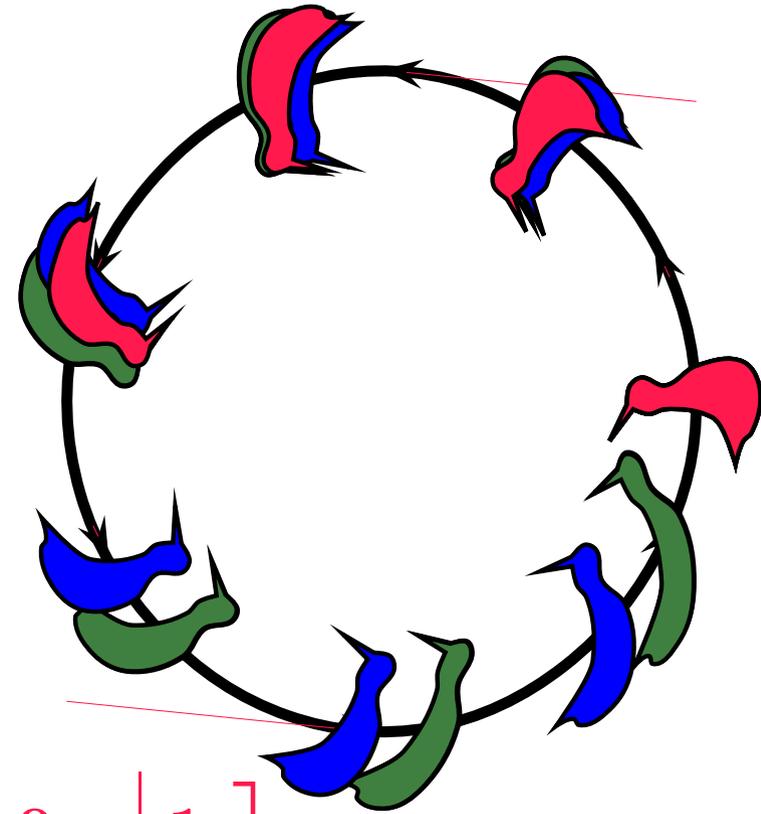
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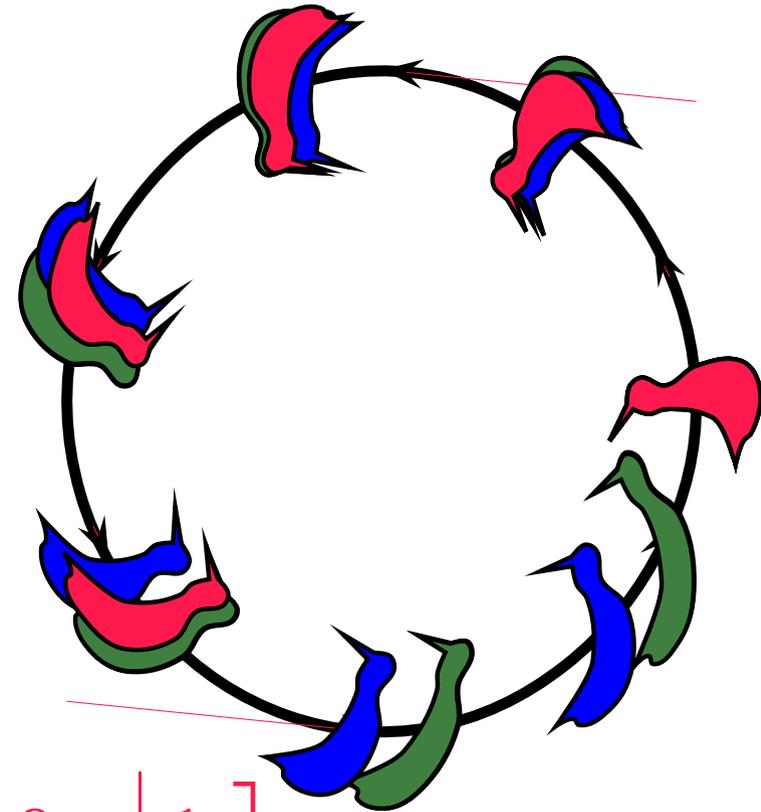
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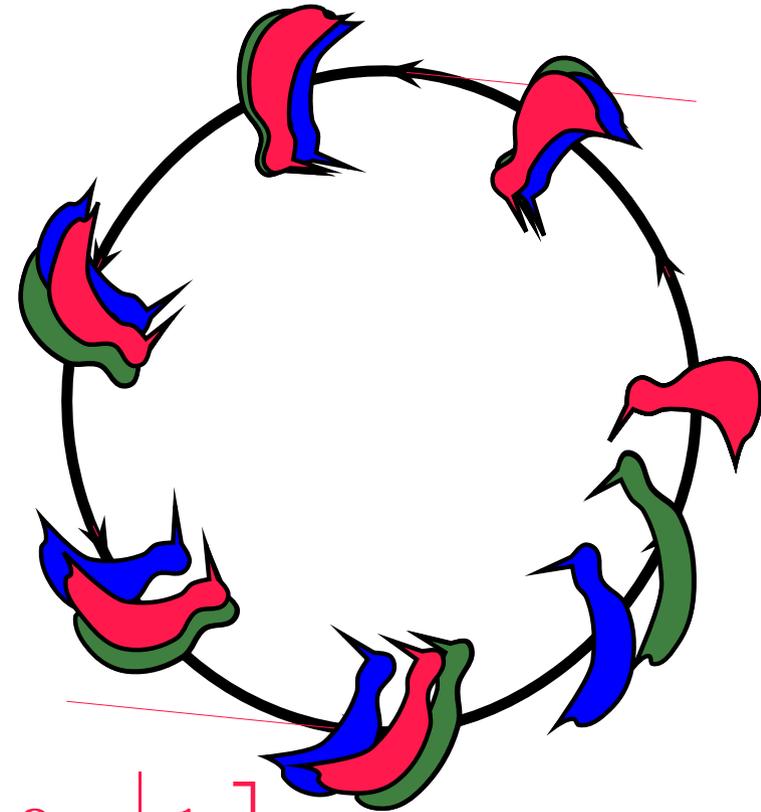
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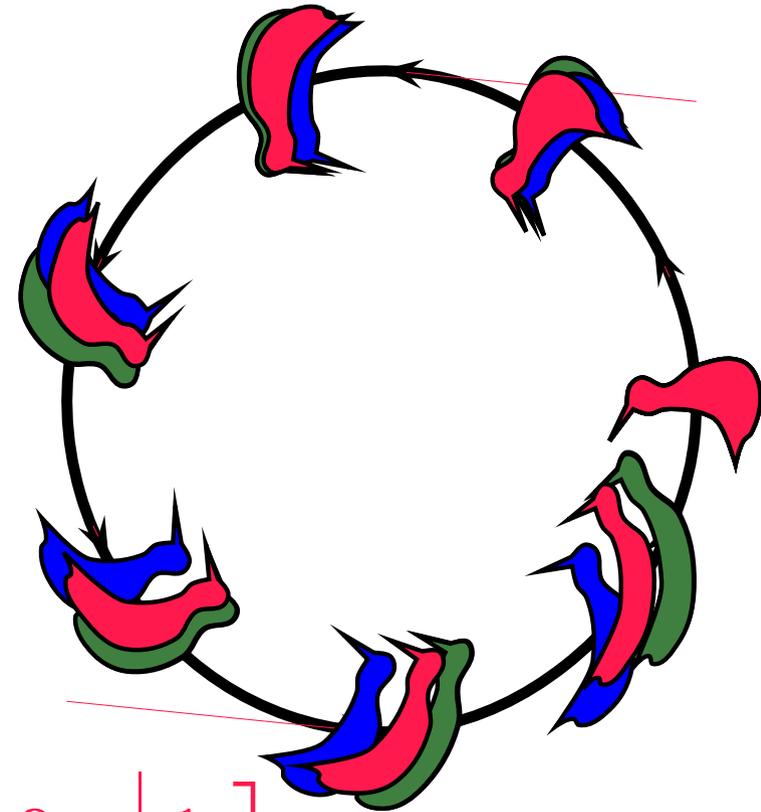
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# Symplectic Runge-Kutta methods

A Runge-Kutta method with  $s$  stages is characterized by three arrays  $A, b, c$ , where  $A$  is an  $s \times s$  matrix and  $b$  and  $c$  are  $s$ -dimensional vectors.

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These quantities, together with the output approximation  $y_n \approx y(t_n)$ , are computed by

$$Y_i = y_{n-1} + h \sum_{j=1}^s a_{ij} F_j, \quad i = 1, 2, \dots, s,$$

$$y_n = y_{n-1} + h \sum_{i=1}^s b_i F_i.$$

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$$\frac{c \mid A}{\mid b^T} = \frac{\frac{1}{2} \mid \frac{1}{2}}{\mid 1}$$

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We recall two examples, the mid-point rule method and the 2-stage Gauss method:

$$\begin{array}{c|c} c & A \\ \hline & b^T \end{array} = \begin{array}{c|c} \frac{1}{2} & \frac{1}{2} \\ \hline & 1 \end{array} \quad \text{and} \quad \begin{array}{c|c} c & A \\ \hline & b^T \end{array} = \begin{array}{c|cc} \frac{3-\sqrt{3}}{6} & \frac{3-2\sqrt{3}}{12} & \frac{1}{4} \\ \frac{3+\sqrt{3}}{6} & \frac{1}{4} & \frac{3+2\sqrt{3}}{12} \\ \hline & \frac{1}{2} & \frac{1}{2} \end{array}$$

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Here is the coefficient tableau, in the form of a partitioned matrix, for this method:

$$\begin{bmatrix} A & U \\ B & V \end{bmatrix} = \left[ \begin{array}{cc|cc} \frac{3+\sqrt{3}}{6} & 0 & 1 & \frac{-3-2\sqrt{3}}{3} \\ -\frac{\sqrt{3}}{3} & \frac{3+\sqrt{3}}{6} & 1 & \frac{3+2\sqrt{3}}{3} \\ \hline \frac{1}{2} & \frac{1}{2} & 1 & 0 \\ \frac{1}{2} & -\frac{1}{2} & 0 & -1 \end{array} \right]$$

For input  $y_1^{[n-1]}$  and  $y_2^{[n-1]}$  to step number  $n$ , the stages and the output values are computed by

$$Y_1 = a_{11}hF_1 + a_{12}hF_2 + u_{11}y_1^{[n-1]} + u_{12}y_2^{[n-1]}$$

$$Y_2 = a_{21}hF_1 + a_{22}hF_2 + u_{21}y_1^{[n-1]} + u_{22}y_2^{[n-1]}$$

$$y_1^{[n]} = b_{11}hF_1 + b_{12}hF_2 + v_{11}y_1^{[n-1]} + v_{12}y_2^{[n-1]}$$

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Substitute the coefficients from the matrices  $A, U, B, V$ :

$$Y_1 = \frac{3+\sqrt{3}}{6}hF_1 + y_1^{[n-1]} - \frac{3+2\sqrt{3}}{3}y_2^{[n-1]}$$

$$Y_2 = -\frac{\sqrt{3}}{3}hF_1 + \frac{3+\sqrt{3}}{6}hF_2 + y_1^{[n-1]} + \frac{3+2\sqrt{3}}{3}y_2^{[n-1]}$$

$$y_1^{[n]} = \frac{1}{2}hF_1 + \frac{1}{2}hF_2 + y_1^{[n-1]}$$

$$y_2^{[n]} = \frac{1}{2}hF_1 - \frac{1}{2}hF_2 - y_2^{[n-1]}$$

**Theorem 3** *The new general linear method has order 4.*

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**Proof.** Given an input approximation

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we need to verify that the output is

$$y^{[1]} = \begin{bmatrix} y(x_0) + hy'(x_0) + \frac{1}{2}h^2y''(x_0) + \frac{1}{6}h^3y^{(3)} + \\ \frac{1}{24}h^4y^{(4)} + O(h^5) \\ \frac{\sqrt{3}}{12}h^2y''(x_0) + \frac{\sqrt{3}}{12}h^3y^{(3)}(x_0) + \frac{7\sqrt{3}}{216}h^4y^{(4)}(x_0) + \\ \frac{9+5\sqrt{3}}{216}h^4\frac{\partial f}{\partial y}y^{(4)}(x_0) + O(h^5) \end{bmatrix}, \quad (2)$$

**Theorem 3** *The new general linear method has order 4.*

**Proof.** Given an input approximation

$$y^{[0]} = \begin{bmatrix} y(x_0) \\ \frac{\sqrt{3}}{12} h^2 y''(x_0) - \frac{\sqrt{3}}{108} h^4 y^{(4)}(x_0) + \frac{9+5\sqrt{3}}{216} h^4 \frac{\partial f}{\partial y} y^{(4)}(x_0) \end{bmatrix}, \quad (1)$$

we need to verify that the output is

$$y^{[1]} = \begin{bmatrix} y(x_0) + hy'(x_0) + \frac{1}{2}h^2y''(x_0) + \frac{1}{6}h^3y^{(3)} + \\ \frac{1}{24}h^4y^{(4)} + O(h^5) \\ \frac{\sqrt{3}}{12}h^2y''(x_0) + \frac{\sqrt{3}}{12}h^3y^{(3)}(x_0) + \frac{7\sqrt{3}}{216}h^4y^{(4)}(x_0) + \\ \frac{9+5\sqrt{3}}{216}h^4\frac{\partial f}{\partial y}y^{(4)}(x_0) + O(h^5) \end{bmatrix}, \quad (2)$$

found by replacing  $x_0$  by  $x_1 = x_0 + h$  in (1) and expanding about  $x_0$ .

By Taylor expansions we find

$$Y_1 = y\left(x_0 + h\frac{3+\sqrt{3}}{6}\right) + \frac{9+5\sqrt{3}}{108}h^3 y^{(3)}(x_0) + O(h^4),$$

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$$Y_1 = y\left(x_0 + h\frac{3+\sqrt{3}}{6}\right) + \frac{9+5\sqrt{3}}{108}h^3 y^{(3)}(x_0) + O(h^4),$$
$$hF_1 = hy'\left(x_0 + h\frac{3+\sqrt{3}}{6}\right) + \frac{9+5\sqrt{3}}{108}h^4 \frac{\partial f}{\partial y} y^{(3)}(x_0) + O(h^5), \quad (3)$$

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Using (3) and (4), evaluate  $y^{[1]} = hAF + Vy^{[0]}$  by Taylor expansions, to obtain agreement with (2).

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Now consider the symplectic property of the new method.

For a general linear method to be symplectic, there would need to exist a diagonal matrix  $D$  and a symmetric matrix  $G$ , each of them positive definite, such that

$$DA + A^T D = B^T G B, \quad G = V^T G V, \quad DU = B^T G V.$$

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In the case of the new method, these are easy to check

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To actually use a method like this, there has to be a starting method to prepare for the very first step. This can be provided by the method

$$\left[ \begin{array}{cc|c} \frac{3+\sqrt{3}}{6} & 0 & 1 \\ -\frac{3+\sqrt{3}}{3} & \frac{3+\sqrt{3}}{6} & 1 \\ \hline 0 & 0 & 1 \\ \frac{\sqrt{3}-1}{8} & \frac{1-\sqrt{3}}{8} & 0 \end{array} \right]$$

# Preservation of quadratic invariants

If  $M$  is a symmetric matrix then the quadratic function

$$\Phi(y) = y^T M y$$

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but for a general linear method satisfying the symplectic property, we will be happy if

$$\sum_{i,j=1}^r g_{ij} \left( (y_i^{[n]})^T M (y_j^{[n]}) \right) = \sum_{i,j=1}^r g_{ij} \left( (y_i^{[n-1]})^T M (y_j^{[n-1]}) \right).$$

After a little manipulation, and using the conditions that

$$V^T G V = G,$$

$$B^T G V = D U,$$

$$B^T G B = D A + A^T D,$$

it is found that

$$\begin{aligned} & \sum_{i,j=1}^r g_{ij} (y_i^{[n]})^T M(y_j^{[n]}) - \sum_{i,j=1}^r g_{ij} (y_i^{[n-1]})^T M(y_j^{[n-1]}) \\ &= 2h \sum_{i=1}^s d_i F_i^T M Y_i \\ &= 0. \end{aligned}$$

As an example of this result, consider the differential equation system due to Euler

$$A\dot{w}_1 = (B - C)w_2w_3,$$

$$B\dot{w}_2 = (C - A)w_3w_1,$$

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This differential equation system has two quadratic invariants:

$$E = Aw_1^2 + Bw_2^2 + Cw_3^2,$$

$$F = A^2w_1^2 + B^2w_2^2 + C^2w_3^2.$$

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For the case

$$[A, B, C] = [4, 3, 2], \quad y_0 = [1, 1, 0]^T.$$

and a stepsize  $h = 0.1$ , the method was applied for  $n = 100,000$  steps.

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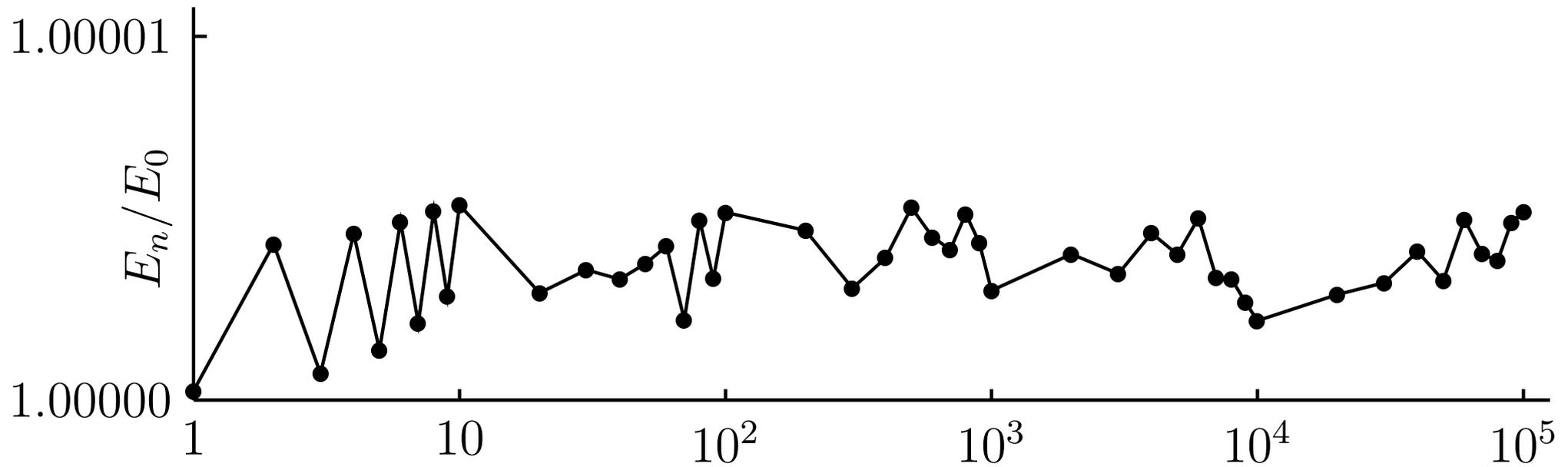
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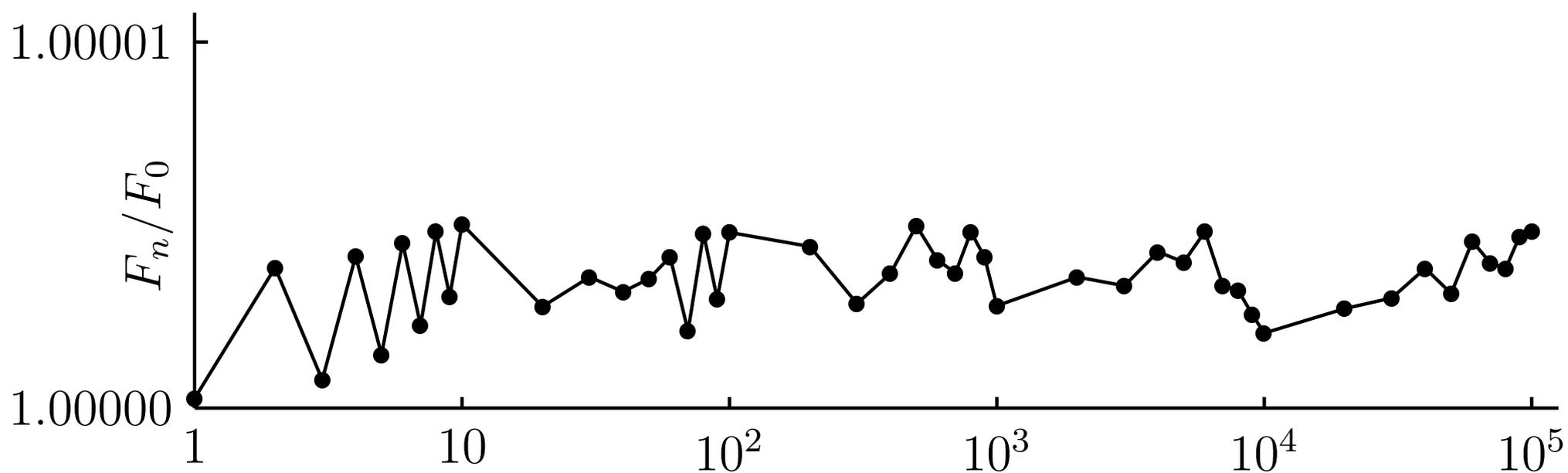
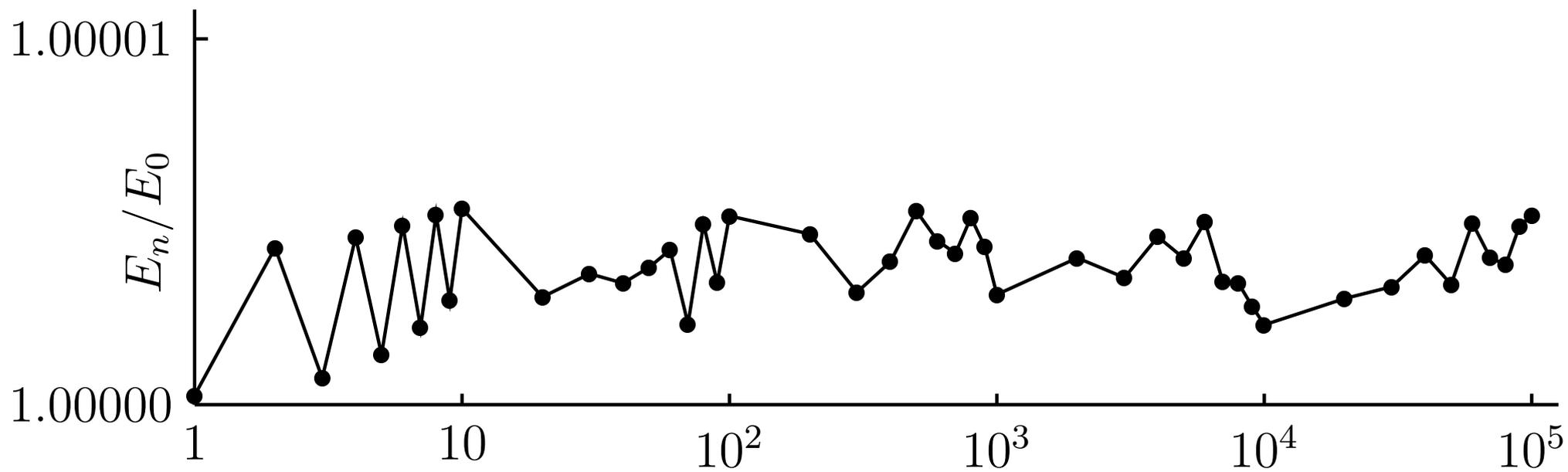
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Results are shown on the next page.





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Such methods work well in preliminary numerical experiments.

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