§24. General and Accurate Weighting Scheme for Collisional δf Particle Simulation

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Let us solve linearized drift kinetic equation

$$\frac{D}{Dt}f_1 = -\vec{v_d} \cdot \nabla f_0 + C(f_0, f_1) \tag{1}$$

from the dynamics of a finite number of particles (markers), where the notation D/Dt(f) denotes

$$\frac{D}{Dt}f = \frac{\partial f}{\partial t} + (\vec{v_{\parallel}} + \vec{v_d}) \cdot \nabla f - C(f, f_0).$$
(2)

The distribution function f_1 is represented as

$$f_1(\vec{x}, \vec{v}, t) = \sum_j w_j \delta(\vec{x} - \vec{x}_j(t)) \delta(\vec{v} - \vec{v}_j(t)).$$
(3)

The particle weights w are calculated from one of \mathbb{C}

$$\dot{w} = \frac{1}{g} \left[-\int w S_M dw - \vec{v_d} \cdot \nabla f_0 + C(f_0, f_1) \right],\tag{4}$$

where S_M is the marker source used to control marker population during simulation and gis marker density[1]. The calculation of particle weight takes a central position in a δf simulation. It is demonstrated that valid results essentially rely on the correct evaluation of marker density gin weight calculation. Previous weighting schemes including the nonlinear weighting scheme[2] employ an assumed g in weight equation for advancing particle weights. Such a scheme is ineffective or inaccurate to solve drift kinetic equation because of a severe constraint the real marker distribution must be consistent with the assumption during a simulation. Instead using an approximation of gfor advancing particle weights, we solve g directly from its kinetic equation

$$\frac{D}{Dt}g = \int S_M dw. \tag{5}$$

Setting $g = f_0 + g_1$, we obtain a CHUZ GC golovob

$$\frac{D}{D^{t}}g_{1} = -\vec{v_{d}} \cdot \nabla f_{0} + \int S_{M}dw.$$
(6)

We employ a new weight function ω and a marker distribution function $G_M(\vec{x}, \vec{v}, \omega, t)$, and then solve Eq.(6) using the idea of δf method. Let G_M obey the kinetic equation

$$\frac{D}{Dt}G_M + \frac{\partial}{\partial \omega} (\dot{\omega}G_M) = \Omega_M(\vec{x}, \vec{v}, \omega, t)$$
(7)

with $G_M(t=0) = f_0 \delta(\omega)$, and relate to g_1 through

$$g_1(\vec{x}, \vec{v}, t) = \int \omega G_M d\omega. \tag{8}$$

Here a source Ω_M , like S_M , is introduced to control marker population. From the requirement that Eqs.(6)-(8) are consistent, the equation for ω is determined as

$$\dot{\omega} = \frac{1}{h} \left[-\int \omega \Omega_M d\omega - \vec{v_d} \cdot \nabla f_0 + \int S_M dw \right], \quad (9)$$

where distribution function $h(\vec{x}, \vec{v}, t)$ satisfies

 $\frac{D}{Dt}h = \int \Omega_M d\omega. \tag{10}$

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$$\int \Omega_M d\omega = \int S_M dw. \tag{11}$$

Then Eqs.(10) and (5) become the same. We have

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For a marker of index j, we have

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$$g_j = g_{0j} + \omega_j h_j$$
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$$g_j = \frac{1}{1 - \omega_j} f_{0j}. \tag{14}$$

Substituting Eq.(14) into Eqs.(4) and (9), we obtain weight equations for a marker as follows

$$\dot{w} = \frac{1-\omega}{f_0} \left[-\int w S_M dw - \vec{v_d} \cdot \nabla f_0 + C(f_0, f_1) \right],$$
(15)
$$\dot{\omega} = \frac{1-\omega}{f_0} \left[-\int \omega \Omega_M d\omega - \vec{v_d} \cdot \nabla f_0 + \int S_M dw \right].$$
(16)

Now each simulation particle is assigned two weights rather than one, the second weight ω is introduced to effectively evaluate g (exactly saying, g_1), and we can solve Eqs.(1) and (6) simultaneously using one set of markers. Equations (15) and (16) represent a general and accurate weighting scheme. For practical application it is convenient to take $S_M = \nu(t)s(\vec{r})f_0\delta(w)$ and $\Omega_M = \nu(t)s(\vec{r})f_0\delta(\omega)$. This choice means that new Maxwellian markers with $w = \omega = 0$ are added in terms of rate $\nu(t)$ and spatial distribution $s(\vec{r})$. Then the weight equations are simplified to

$$\dot{w} = rac{1-\omega}{f_0} \left[-ec{v_d} \cdot
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 (17)

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