Evaluation of an ensemble based 4D Var assimilation

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Aims and model

- Objective :
  - Compare En4DVar with a classic 4DVar method
- 2D shallow water model

$$\partial_t h + \nabla \cdot \mathbf{q} = 0$$
$$\partial_t \mathbf{q} + \nabla \cdot (\tfrac{1}{h}\mathbf{q} \otimes \mathbf{q} + \tfrac{1}{2} g h^2 Id) = 0$$

Incremental 4DVar vs En4DVar assimilation techniques

Incremental 4DVar assimilation

- Cost function using static covariance matrices $\mathbb{B}$ and $\mathbb{R}$

$$J(\delta X_0) = \frac{1}{2}\sum_{\Omega} ||\delta X_0||_{\mathbb{B}^{-1}} + \frac{1}{2}\sum_{0}^{T}\sum_{\Omega} ||\mathbb{H}(X^b) + \partial_X \mathbb{H}(\partial_X \mathbb{M}(\delta X_0)) - Y||_{\mathbb{R}^{-1}}$$

- Adjoint equation determined by TAPENADE

$$-\partial_t \lambda + (\partial_X \mathbb{M}^{\#})\lambda = \sum_{i=1}^{N} (\partial_X \mathbb{H})^{\#} \mathbb{R}^{-1}(Y - \mathbb{H}(X^b))$$
$$\lambda(t_f) = 0$$

- We deduce the gradient

$$\nabla J(\delta X_0) = \lambda(t_0)$$

En4DVar assimilation

- Cost function using flow dependent background error covariance matrix within the context of the preconditioning techniques $\delta X_0 = \mathbb{B}^{1/2}\delta Z_0$,

$$J(\delta Z_0) = \frac{1}{2}\sum_{\Omega} ||\delta Z_0|| + \frac{1}{2}\sum_{0}^{T}\sum_{\Omega} ||\mathbb{H}(X^b) + \partial_X \mathbb{H} \partial_X \mathbb{M} \mathbb{B}^{1/2} \delta Z_0 - Y||_{\mathbb{R}^{-1}}$$

  where the $\mathbb{B}^{1/2}$ matrix estimated from the difference between each ensemble member and ensemble mean

$$\mathbb{B}^{1/2} \approx \frac{1}{\sqrt{N-1}}(X_0^{b,1} - \bar{X}_0^b, ..., X_0^{b,N} - \bar{X}_0^b)$$

- We estimate the evolution of the $\mathbb{B}^{1/2}$ matrix from the evolution of the ensemble fields in observation space

$$\partial_X \mathbb{H} \partial_X \mathbb{M} \mathbb{B}^{1/2} \approx \frac{1}{\sqrt{N-1}}(\mathbb{H}\mathbb{M}X_0^{b,1} - \mathbb{H}\mathbb{M}\bar{X}_0^b, ..., \mathbb{H}\mathbb{M}X_0^{b,N} - \mathbb{H}\mathbb{M}\bar{X}_0^b)$$

- Localization technique used to eliminate sampling error in state space

$$P_b^{1/2} = (\mathbb{C}^{1/2} \cdot \mathbb{B}_1^{1/2}, ..., \mathbb{C}^{1/2} \cdot \mathbb{B}_N^{1/2})$$

- Minimization performed with **LBFGS algorithm**: limited memory quasi Newton method

Results

Synthetic data

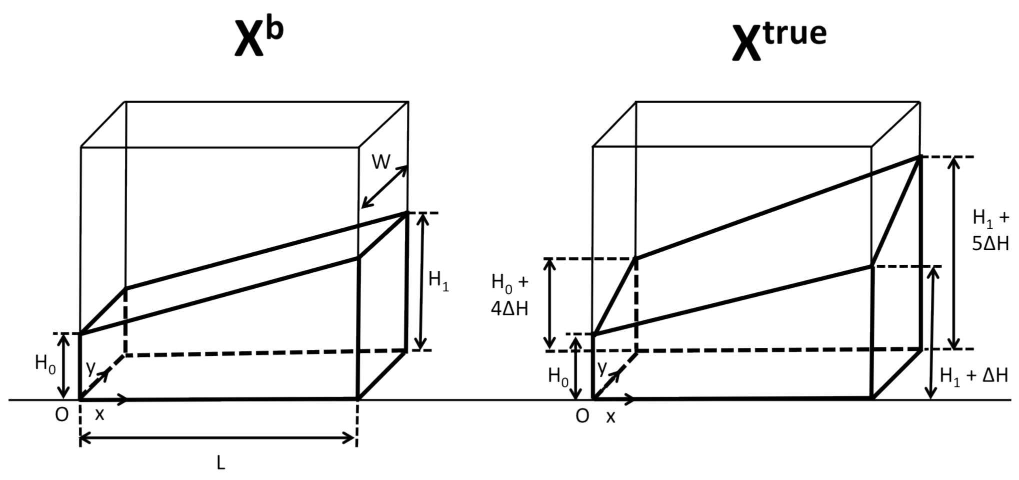

Figure: Background initial state (left) and True initial state (right)

- Background initial condition
  - $L = 25cm$
  - $W = 10cm$
  - $H_0 = 2cm$
  - $H_1 = 7cm$
  - $U(x, y, t_0) = 0$
  - $V(x, y, t_0) = 0$
- Exact initial condition
  - $L = 25cm$
  - $W = 10cm$
  - $H_0 = 2cm$
  - $\Delta H = 0.25cm$
  - $U(x, y, t_0) = \epsilon_0^u(x, y)$
  - $U(x, L, t_0) = \epsilon_0^u(x, L) + 1cm.s^{-1}$
  - $V(x, y, t_0) = \epsilon_0^v(x, y)$
  - $V(W, y, t_0) = \epsilon_0^v(W, y) + 1cm.s^{-1}$

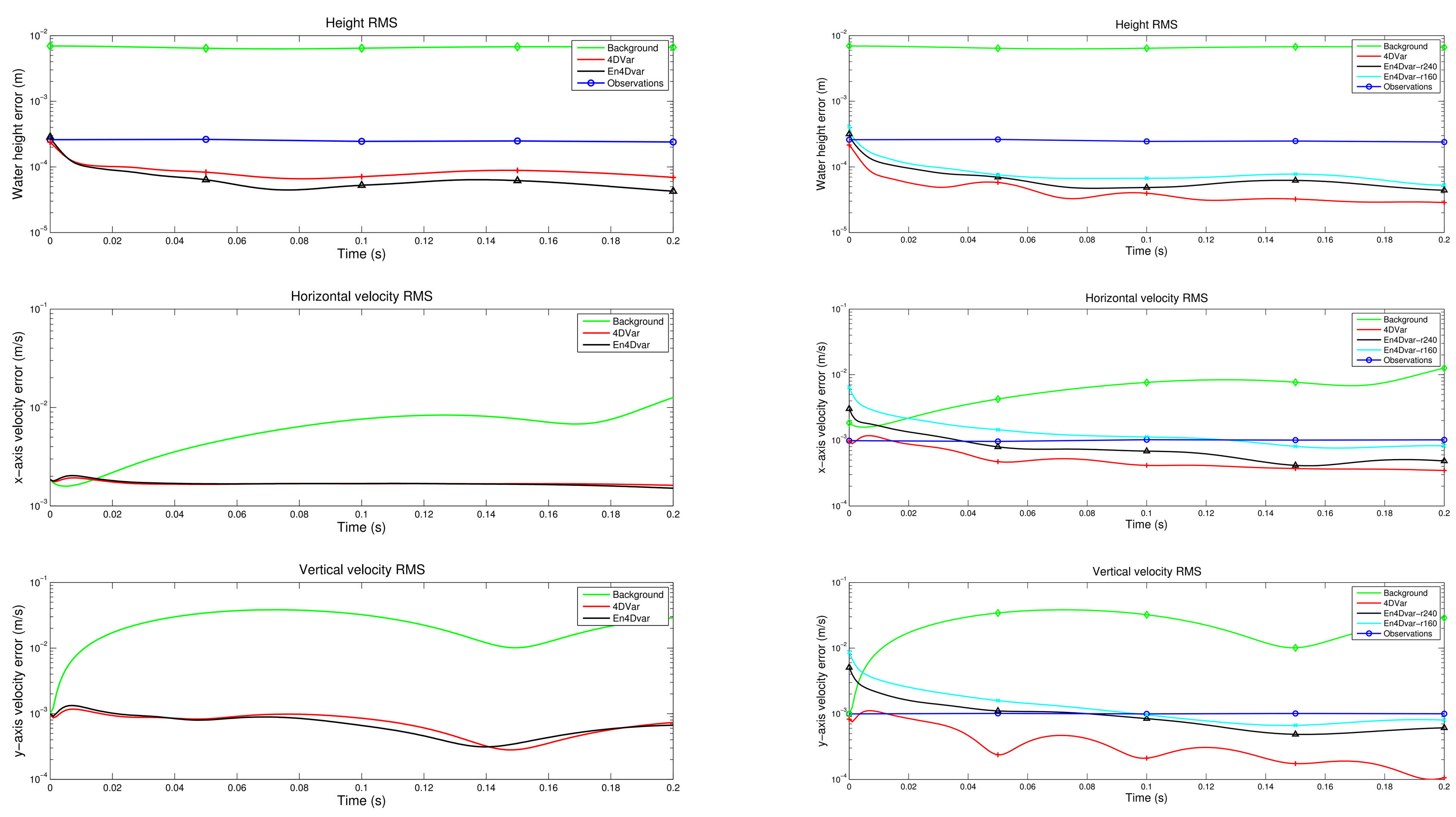

Figure: RMS semilog of the assimilation with the height observations only (left) and both height and velocity observations (right)

- Assimilation with height observations only
  - En4DVar is slightly better than 4DVar
  - Same computation time
  - En4DVar requires more memory space
- Assimilation with height and velocity observations
  - En4DVar requires much more computation time
  - En4DVar leads to better results with a higher truncation mode
  - Higher truncation mode demands higher computation time and memory needs

Experimental data

We only possess the height observations given by the depth sensor (Kinect sensor)

Figure: Experiment configuration with the depth sensor (Kinect sensor)

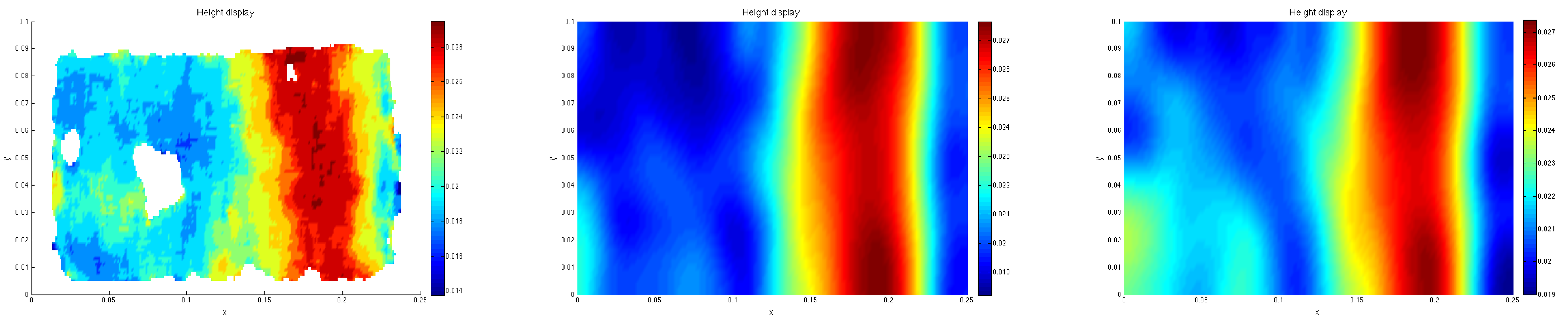

Figure: From left to right: free surface height obtained by the kinect, 4DVar and En4DVar at t=0.06s

Conclusions

- Sensibly the same computational time cost, En4DVar yields better results than the classic 4DVar assimilation when we have only height observations
- En4DVar is easy to implement for any given model. We gain a lot of time with the parallelization computing technique. En4DVar implemented with only one outer loop iteration and needs about 100 iterations for the optimization. Requires a lot of memory.
- 4DVar requires the tangent and adjoint operators. The assimilation converges with 3 outer loop iterations and requires less inner loop iterations for the optimization.

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