

École Doctorale des Sciences de l'Environnement d'Île-de-France

Année Universitaire 2016-2017

Modélisation Numérique
de l'Écoulement Atmosphérique
et Assimilation de Données

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Cours 4

11 Mai 2017

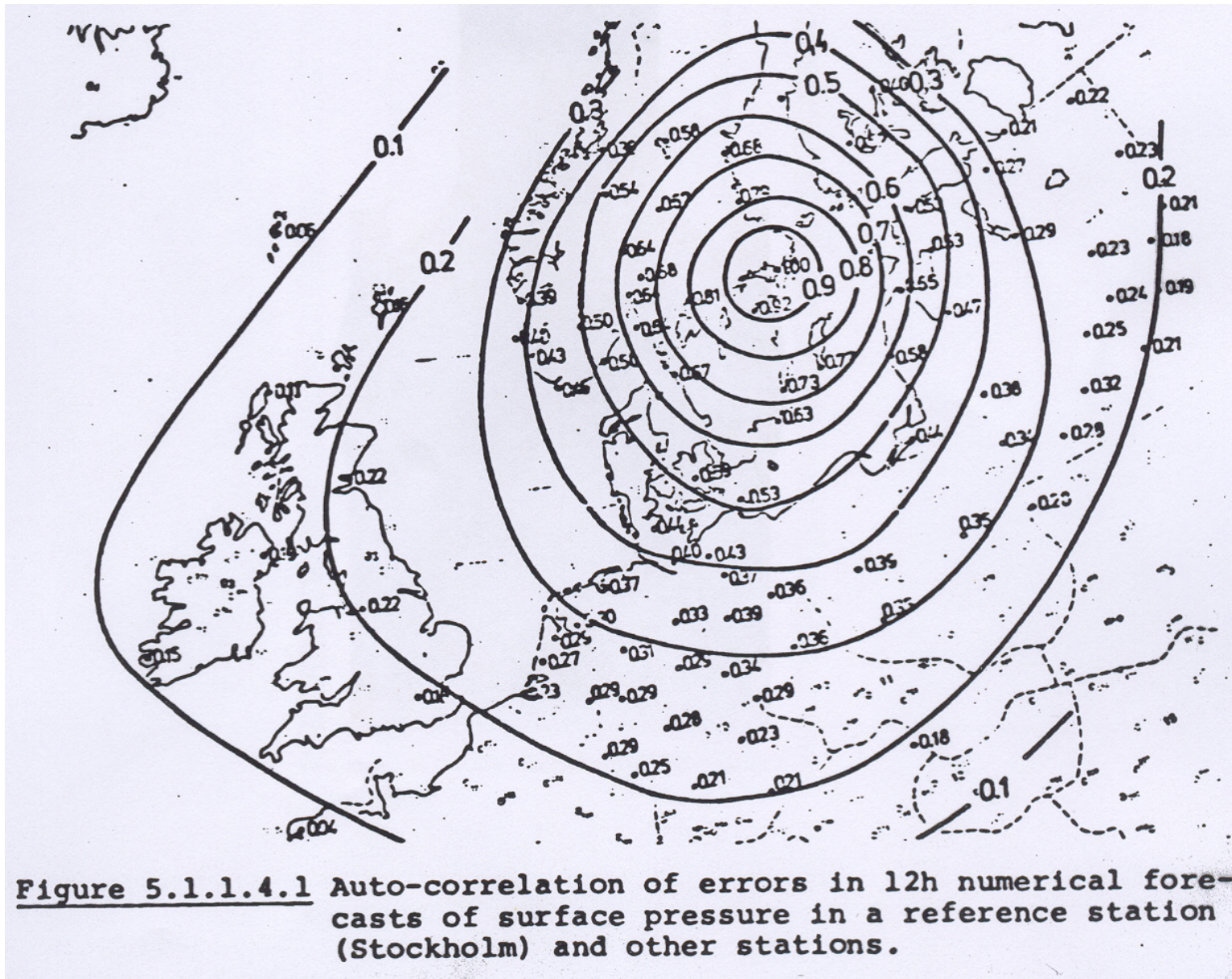


Figure 5.1.1.4.1 Auto-correlation of errors in 12h numerical forecasts of surface pressure in a reference station (Stockholm) and other stations.

After N. Gustafsson

Optimal Interpolation

Random field $\Phi(\xi)$

Observation network $\xi_1, \xi_2, \dots, \xi_p$

For one particular realization of the field, observations

$$y_j = \Phi(\xi_j) + \varepsilon_j, \quad j = 1, \dots, p, \quad \text{making up vector } \mathbf{y} = (y_j)$$

Estimate $x = \Phi(\xi)$ at given point ξ , in the form

$$x^a = \alpha + \sum_j \beta_j y_j = \alpha + \boldsymbol{\beta}^T \mathbf{y}, \quad \text{where } \boldsymbol{\beta} = (\beta_j)$$

α and the β_j 's being determined so as to minimize the expected quadratic estimation error $E[(x-x^a)^2]$

Optimal Interpolation (continued 1)

Solution

$$\begin{aligned}x^a &= E(x) + E(x'y'^T) [E(y'y'^T)]^{-1} [y - E(y)] \\ &= E(x) + C_{xy} [C_{yy}]^{-1} [y - E(y)]\end{aligned}$$

$$\begin{aligned}i. e., \quad \beta^T &= C_{xy} [C_{yy}]^{-1} \\ \alpha &= E(x) - \beta^T E(y)\end{aligned}$$

Estimate is unbiased $E(x-x^a) = 0$

Minimized quadratic estimation error

$$\begin{aligned}E[(x-x^a)^2] &= E(x'^2) - E[(x'^a)^2] \\ &= C_{xx} - C_{xy} [C_{yy}]^{-1} C_{yx}\end{aligned}$$

Estimation made in terms of deviations x' and y' from expectations $E(x)$ and $E(y)$.

Optimal Interpolation (continued 2)

$$x^a = E(x) + E(x'y'^T) [E(y'y'^T)]^{-1} [y - E(y)]$$

$$y_j = \Phi(\xi_j) + \varepsilon_j$$

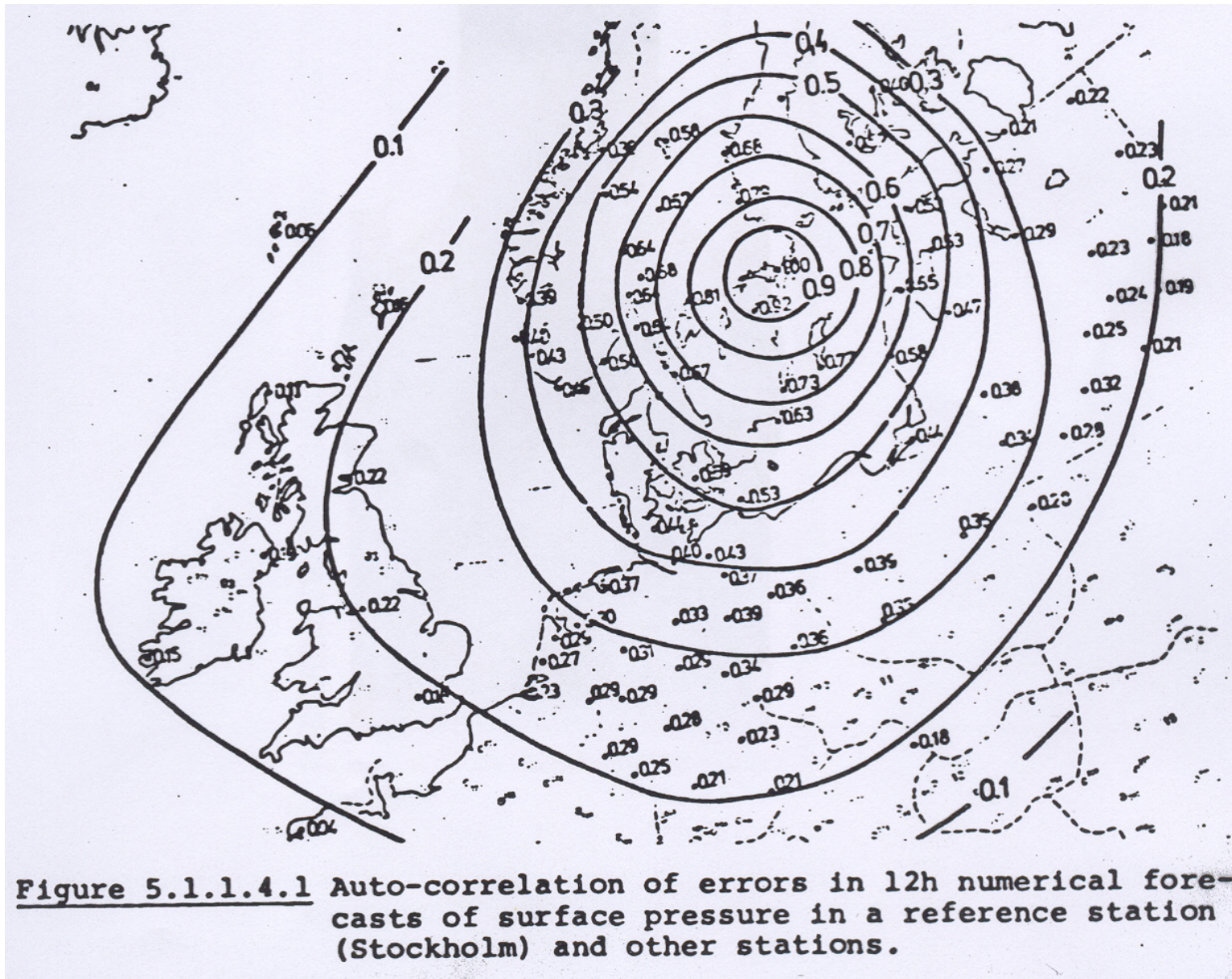
$$E(y_j'y_k') = E[\Phi'(\xi_j) + \varepsilon_j'] [\Phi'(\xi_k) + \varepsilon_k']$$

If observation errors ε_j are mutually uncorrelated, have common variance r , and are uncorrelated with field Φ , then

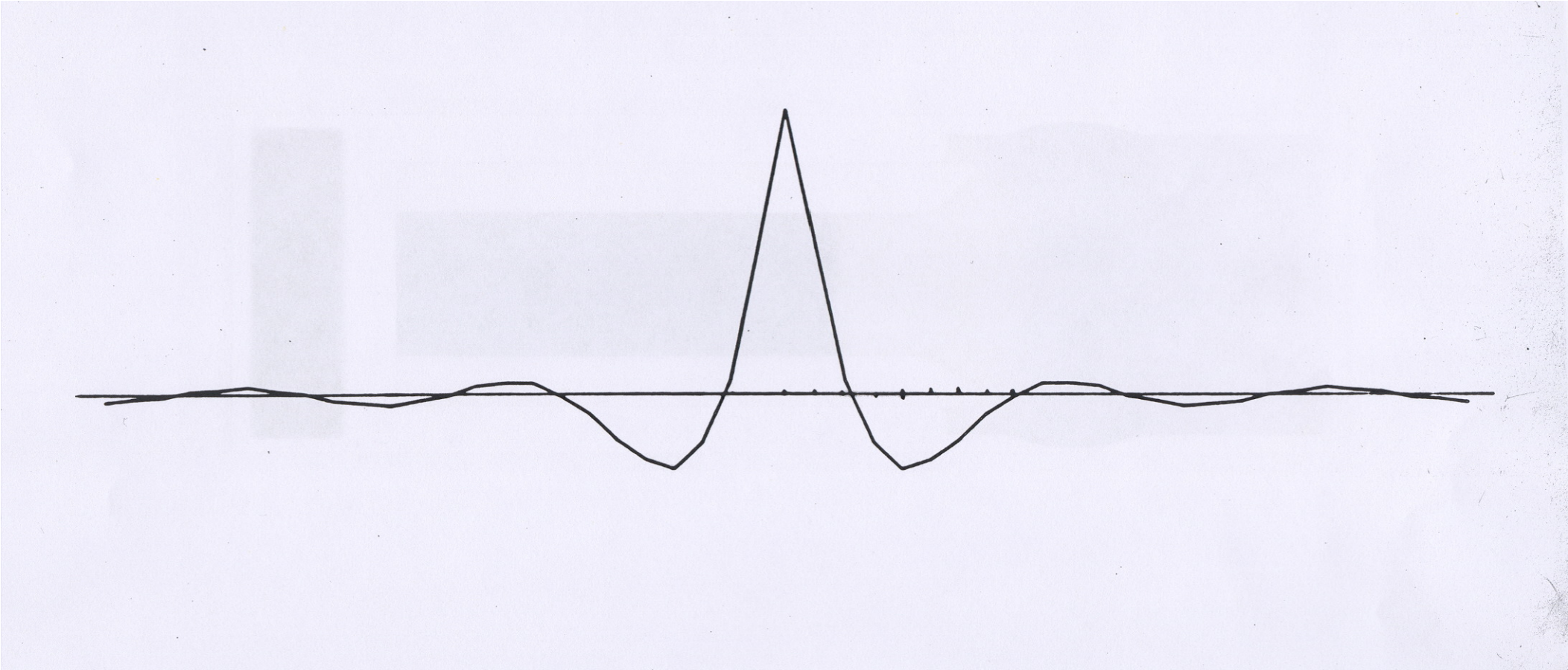
$$E(y_j'y_k') = C_\Phi(\xi_j, \xi_k) + r\delta_{jk}$$

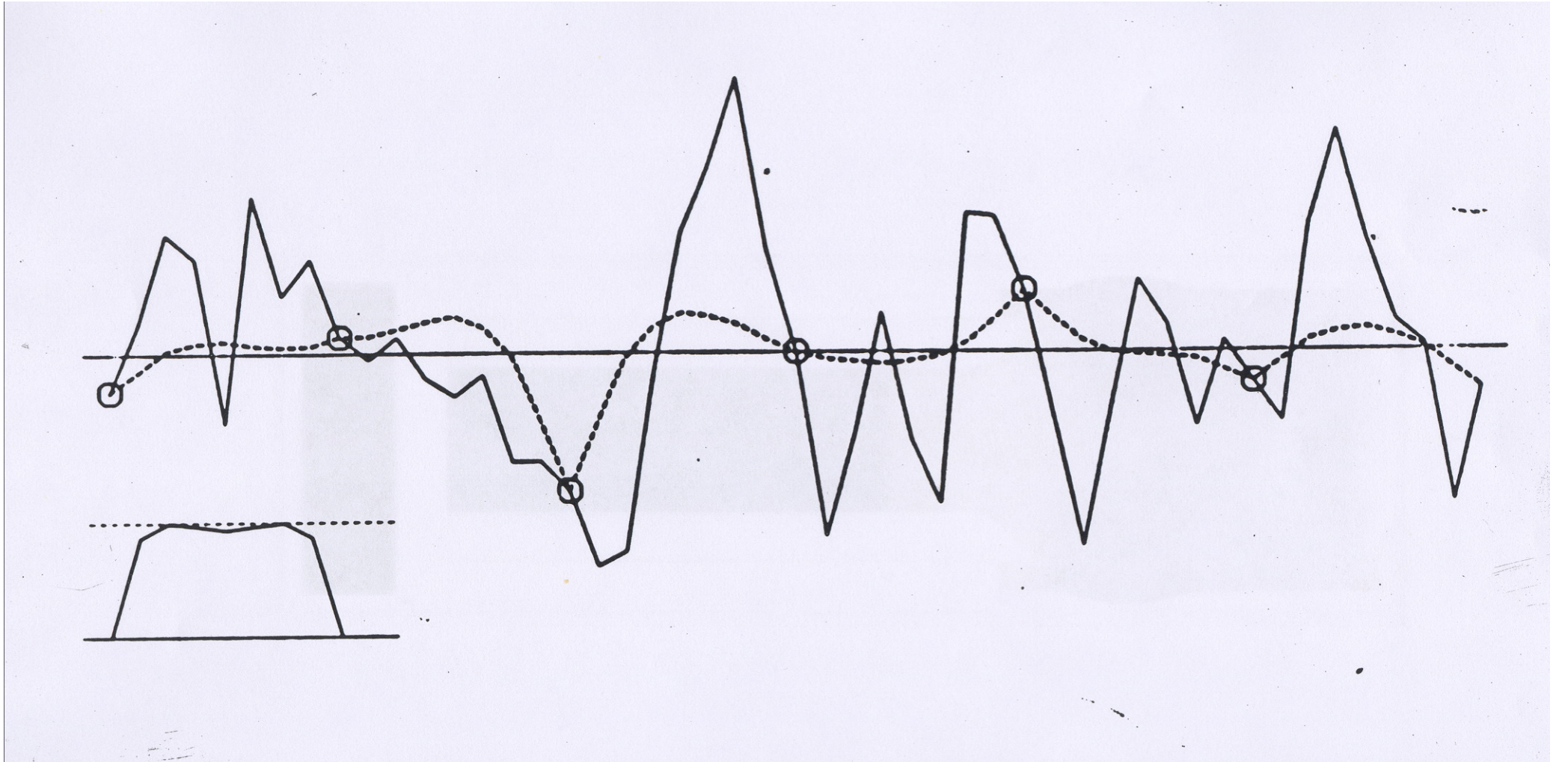
and

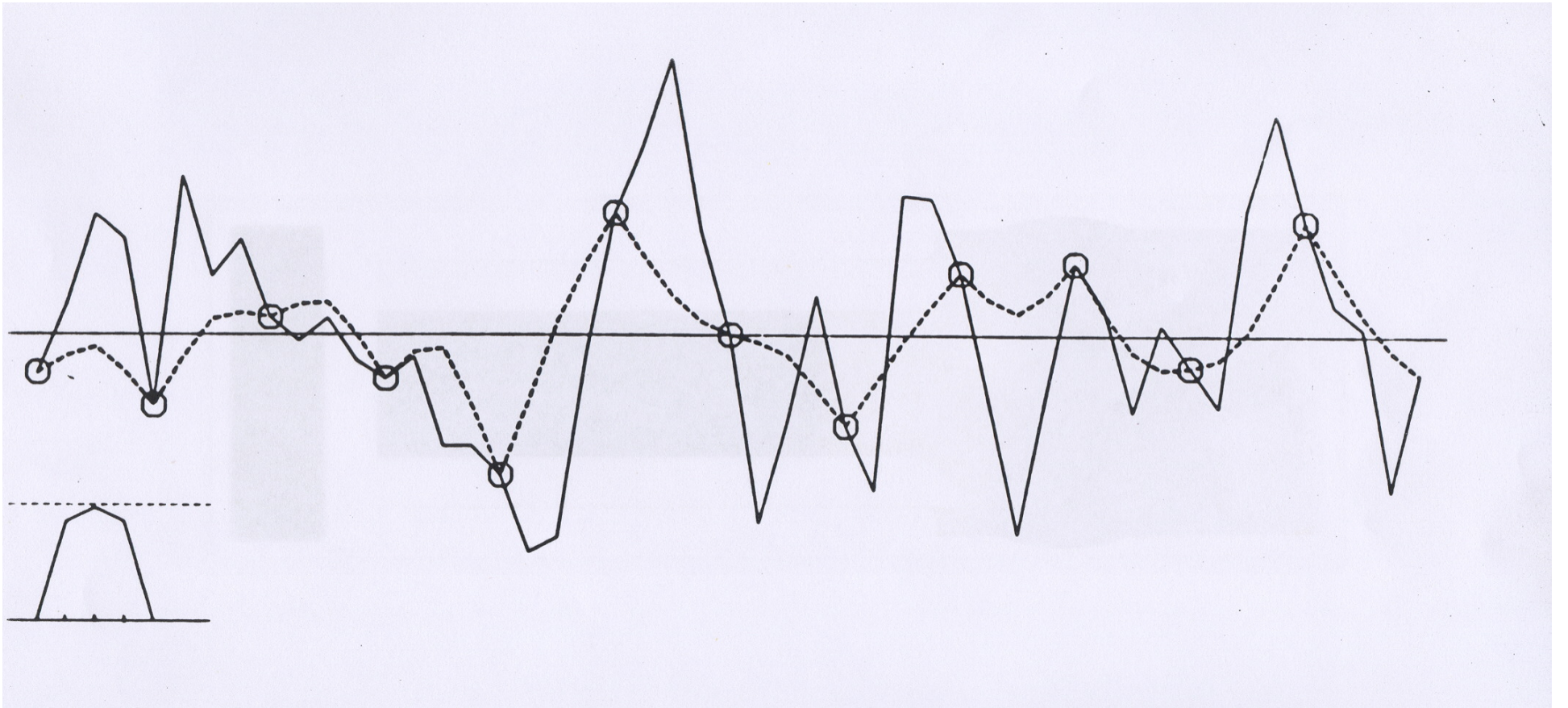
$$E(x'y_j') = C_\Phi(\xi, \xi_j)$$

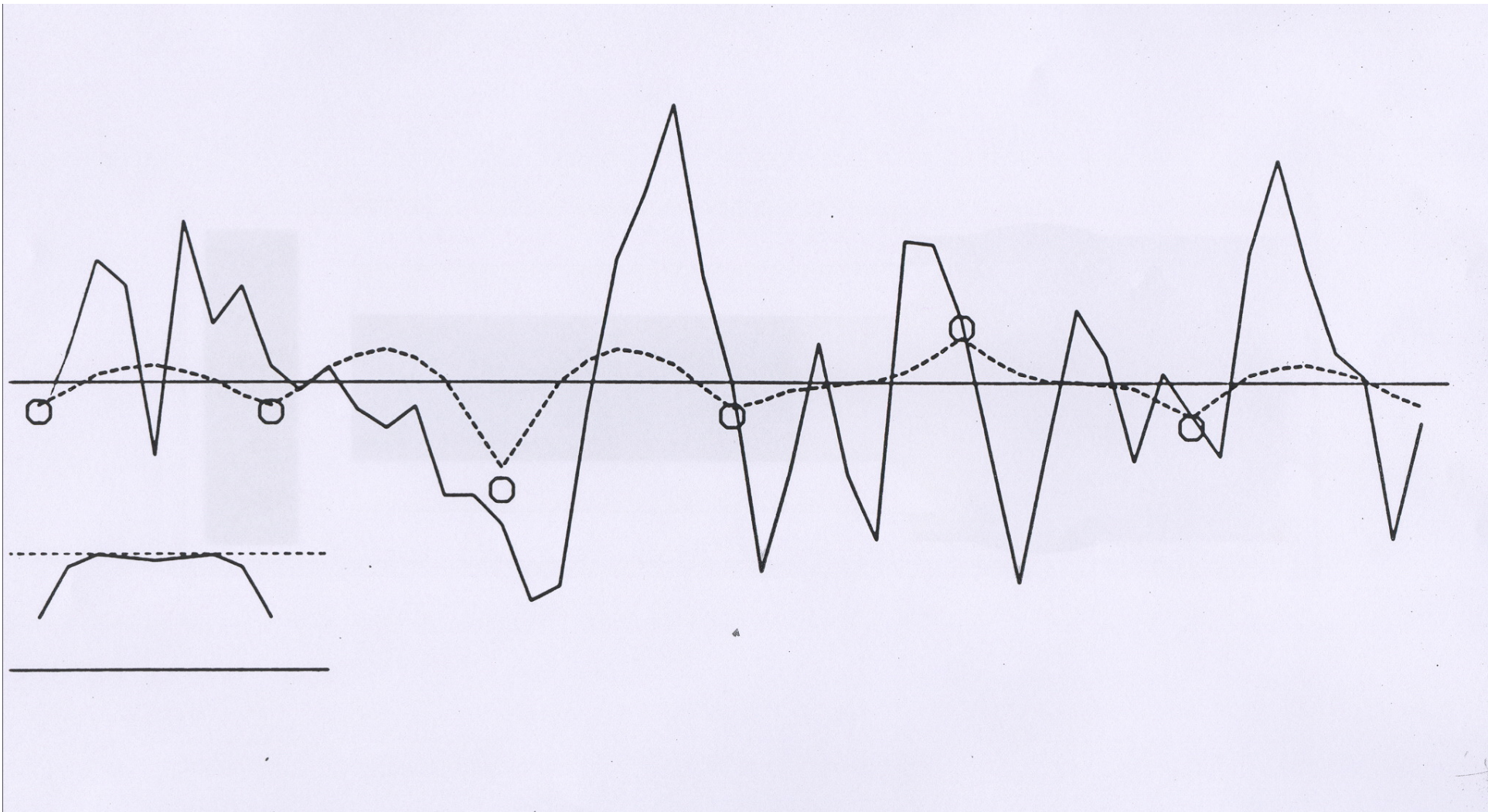


After N. Gustafsson









Optimal Interpolation (continued 3)

$$x^a = E(x) + C_{xy} [C_{yy}]^{-1} [y - E(y)]$$

Vector

$$\mu = (\mu_j) \equiv [C_{yy}]^{-1} [y - E(y)]$$

is independent of variable to be estimated

$$x^a = E(x) + \sum_j \mu_j E(x'y_j')$$

$$\begin{aligned} \Phi^a(\xi) &= E[\Phi(\xi)] + \sum_j \mu_j E[\Phi'(\xi) y_j'] \\ &= E[\Phi(\xi)] + \sum_j \mu_j C_\phi(\xi, \xi_j) \end{aligned}$$

Correction made on background expectation is a linear combination of the p functions $C_\phi(\xi, \xi_j)$

$C_\phi(\xi, \xi_j)$, considered as a function of estimation position ξ , is the *representer* associated with observation y_j .

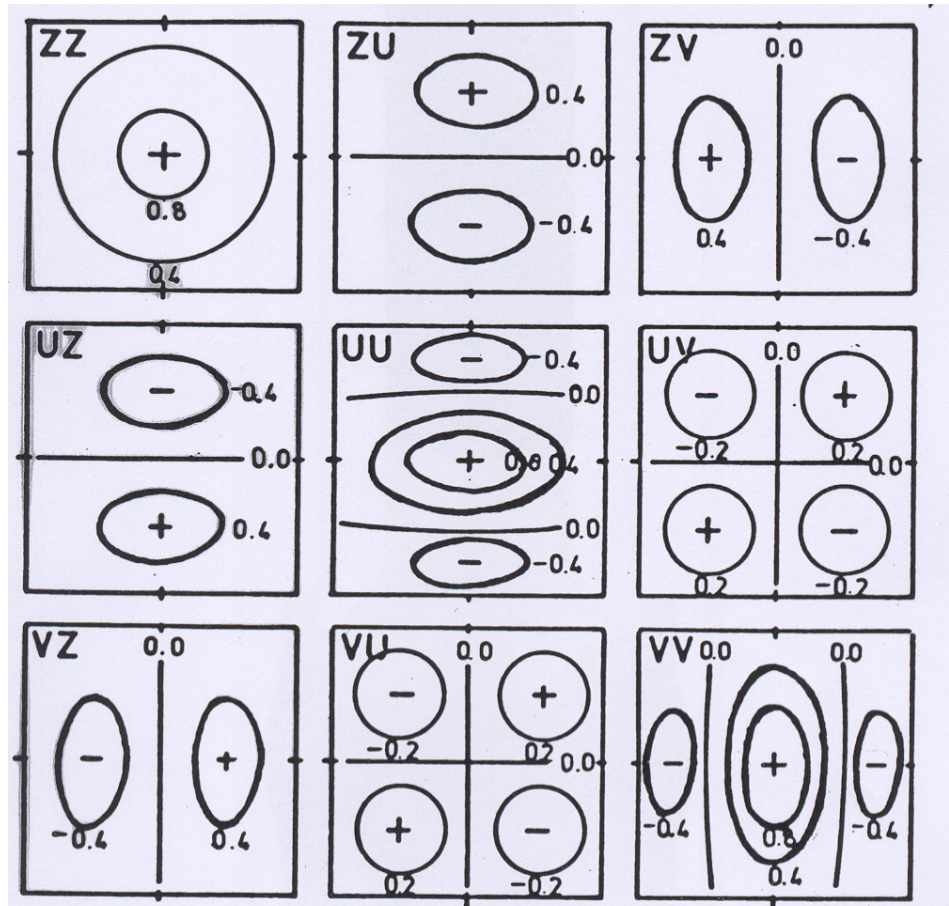
Optimal Interpolation (continued 4)

Univariate interpolation. Each physical field (*e. g.* temperature) determined from observations of that field only.

Multivariate interpolation. Observations of different physical fields are used simultaneously. Requires specification of cross-covariances between various fields.

Cross-covariances between mass and velocity fields can simply be modelled on the basis of geostrophic balance.

Cross-covariances between humidity and temperature (and other) fields still a problem.



4.: Schematic illustration of correlation functions and cross-correlation functions for multi-variate analysis derived by the geostrophic assumption.

After N. Gustafsson

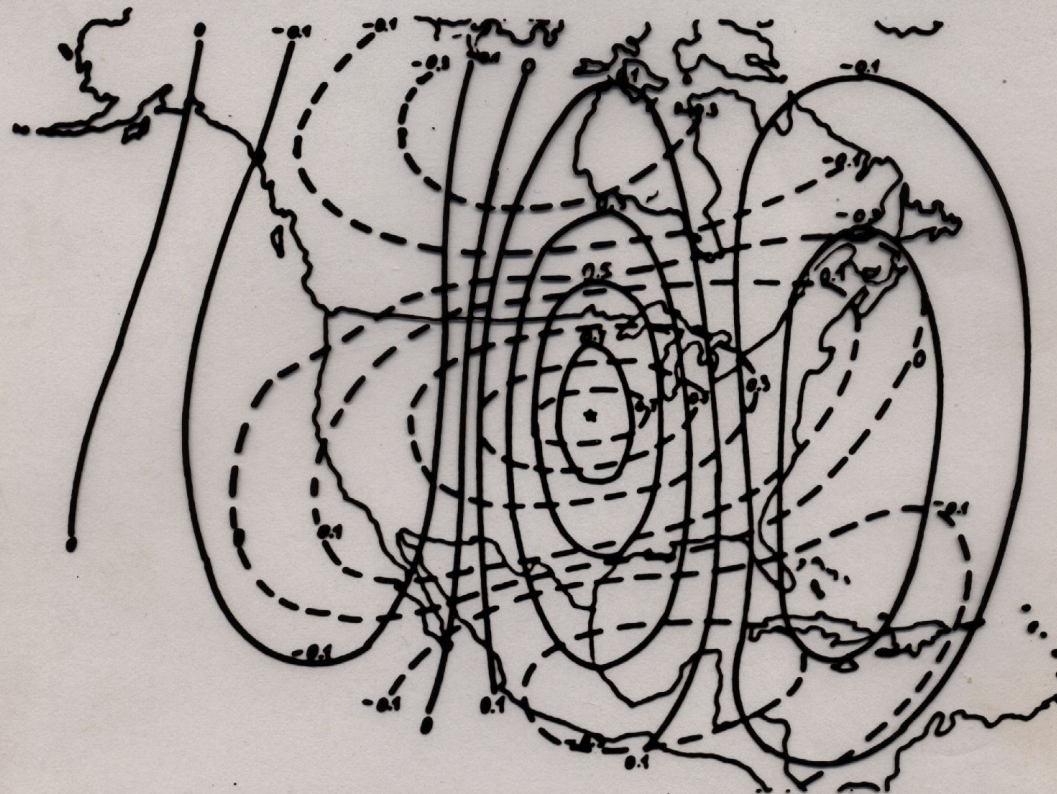
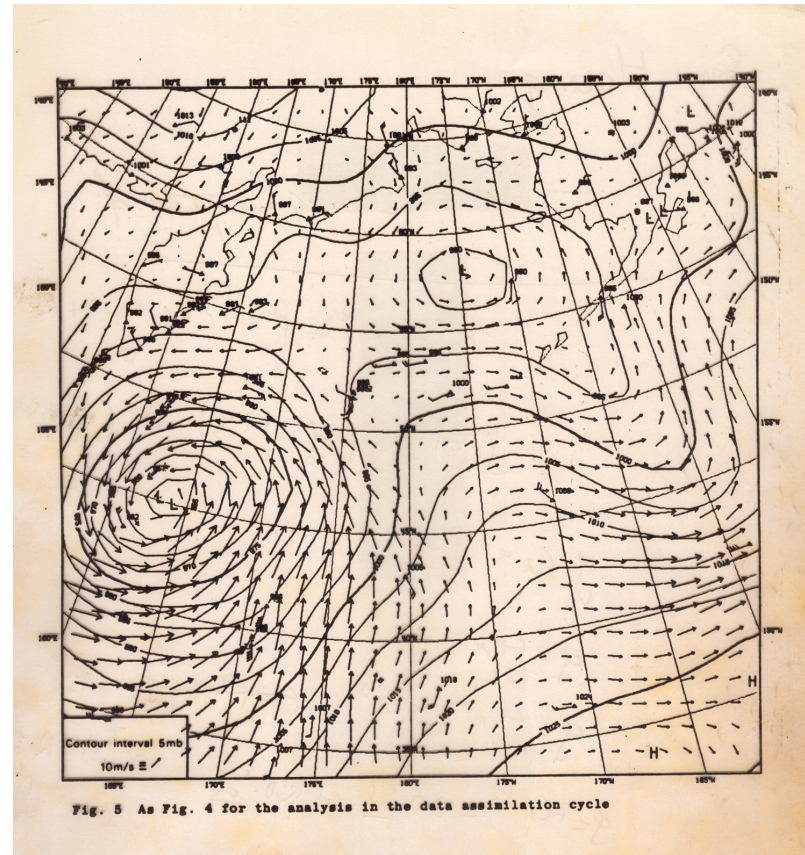
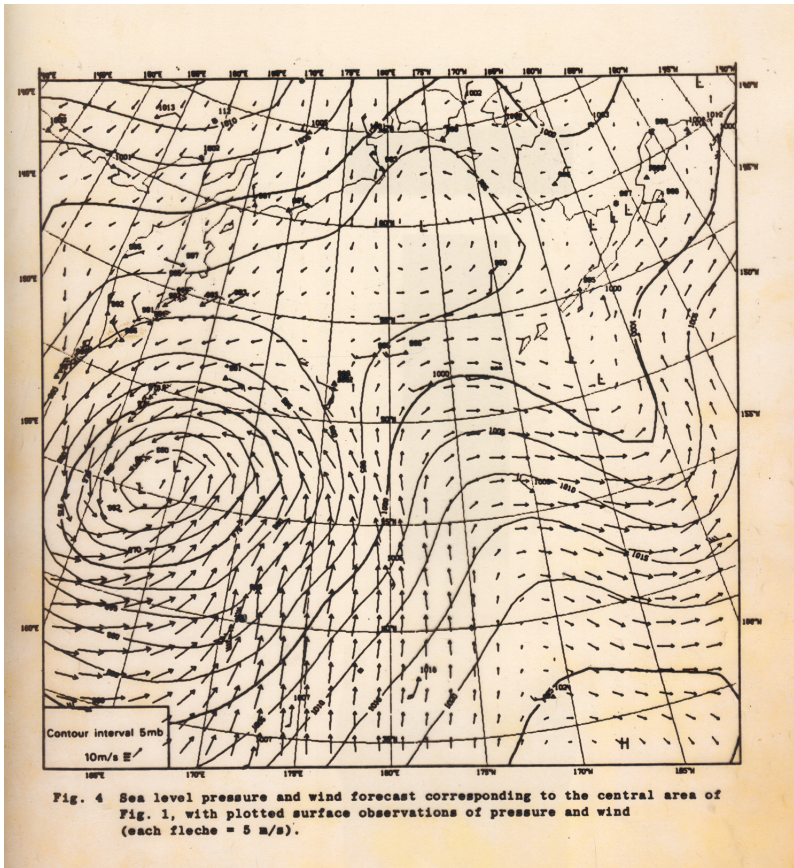


Figure 4.2.4.3: Isolines for the auto-correlation of the 500 mb u-wind component (dashed line) and the auto-correlation of the 500 mb v-wind component (full line). The "star" indicates the position of the reference station. (From Buel (1972)).

After N. Gustafsson



After A. Lorenc, MWR, 1981

1200 GMT 19 January 1979

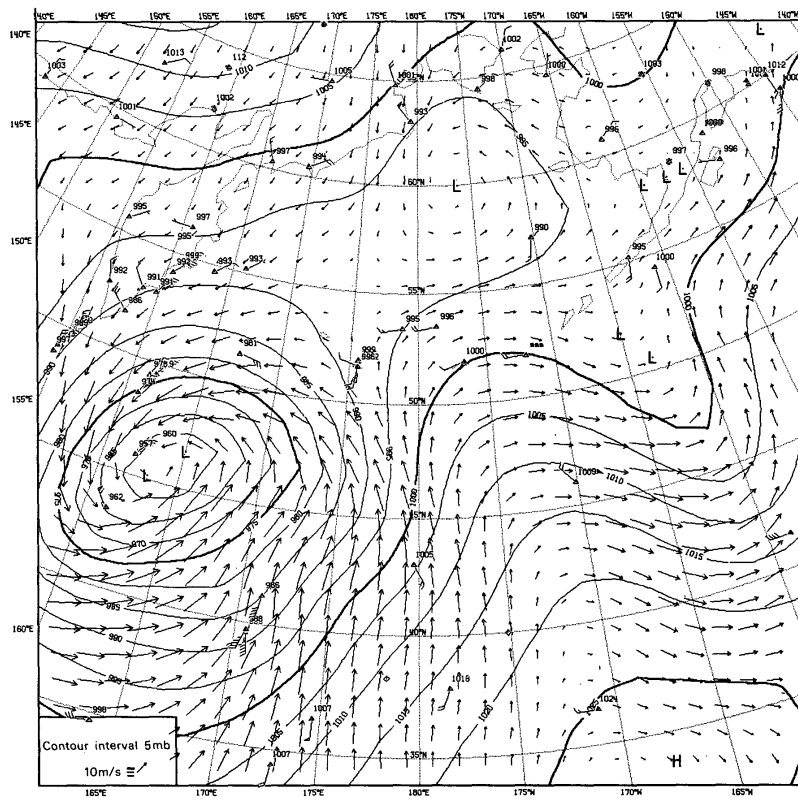


FIG. 14. Sea level pressure and wind forecast corresponding to the central area of Fig. 11, with plotted surface observations of sea level pressure and wind (each barb = 5 m s⁻¹).

1200 GMT 19 January 1979

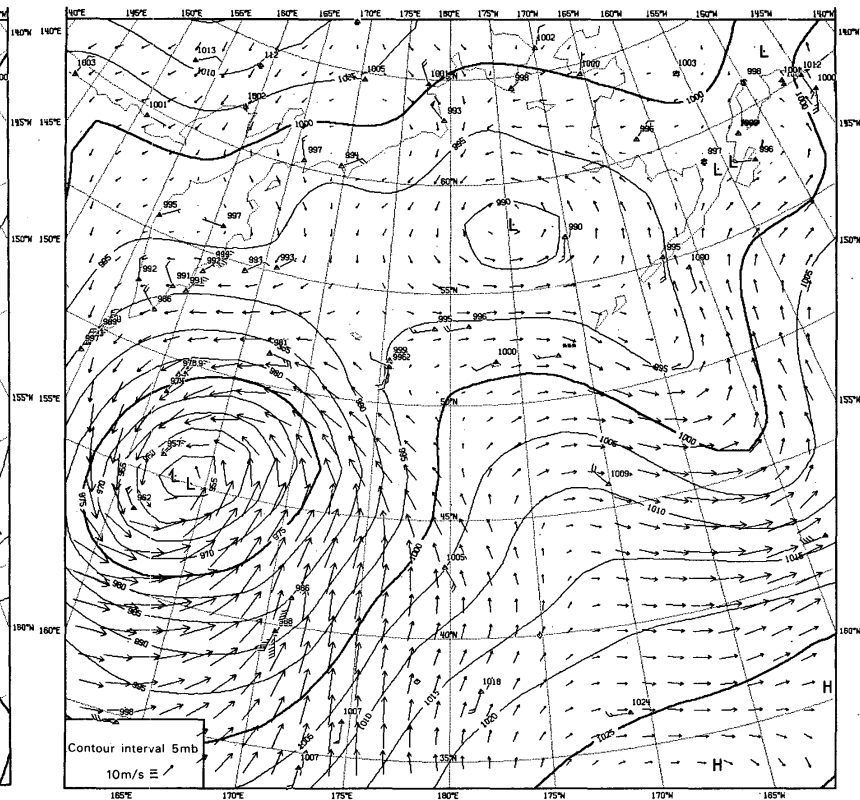


FIG. 15. As in Fig. 14 for the analysis in the data-assimilation cycle.

After A. Lorenc, MWR, 1981

Optimal Interpolation (continued 5)

Observation vector \mathbf{y}

Estimation of a scalar x

$$x^a = E(x) + C_{xy} [C_{yy}]^{-1} [\mathbf{y} - E(\mathbf{y})]$$

$$\begin{aligned} p^a &\equiv E[(x-x^a)^2] = E(x'^2) - E[(x'^a)^2] \\ &= C_{xx} - C_{xy} [C_{yy}]^{-1} C_{yx} \end{aligned}$$

Estimation of a vector \mathbf{x}

$$\mathbf{x}^a = E(\mathbf{x}) + C_{xy} [C_{yy}]^{-1} [\mathbf{y} - E(\mathbf{y})]$$

$$\begin{aligned} \mathbf{P}^a &\equiv E[(\mathbf{x}-\mathbf{x}^a) (\mathbf{x}-\mathbf{x}^a)^T] = E(\mathbf{x}'\mathbf{x}'^T) - E(\mathbf{x}'^a \mathbf{x}'^{aT}) \\ &= C_{xx} - C_{xy} [C_{yy}]^{-1} C_{yx} \end{aligned}$$

Optimal Interpolation (continued 6)

$$\mathbf{x}^a = E(\mathbf{x}) + \mathbf{C}_{xy} [\mathbf{C}_{yy}]^{-1} [\mathbf{y} - E(\mathbf{y})]$$

$$\mathbf{P}^a = \mathbf{C}_{xx} - \mathbf{C}_{xy} [\mathbf{C}_{yy}]^{-1} \mathbf{C}_{yx}$$

If probability distribution for couple (\mathbf{x}, \mathbf{y}) is Gaussian (with, in particular, covariance matrix

$$\mathbf{C} \equiv \begin{pmatrix} \mathbf{C}_{xx} & \mathbf{C}_{xy} \\ \mathbf{C}_{yx} & \mathbf{C}_{yy} \end{pmatrix}$$

then Optimal Interpolation achieves Bayesian estimation, in the sense that

$$P(\mathbf{x} | \mathbf{y}) = \mathcal{N}[\mathbf{x}^a, \mathbf{P}^a]$$

Best Linear Unbiased Estimate

State vector x , belonging to state space \mathcal{S} ($\dim \mathcal{S} = n$), to be estimated.

Available data in the form of

- A ‘background’ estimate (*e. g.* forecast from the past), belonging to state space, with dimension n

$$x^b = x + \zeta^b$$

- An additional set of data (*e. g.* observations), belonging to observation space, with dimension p

$$y = Hx + \varepsilon$$

H is known linear observation operator.

Assume probability distribution is known for the couple (ζ^b, ε) .

Assume $E(\zeta^b) = 0$, $E(\varepsilon) = 0$, $E(\zeta^b \varepsilon^T) = 0$ (not restrictive)

Set $E(\zeta^b \zeta^{bT}) = P^b$ (also often denoted B), $E(\varepsilon \varepsilon^T) = R$

Best Linear Unbiased Estimate (continuation 1)

$$\mathbf{x}^b = \mathbf{x} + \boldsymbol{\zeta}^b \quad (1)$$

$$\mathbf{y} = H\mathbf{x} + \boldsymbol{\varepsilon} \quad (2)$$

A probability distribution being known for the couple $(\boldsymbol{\zeta}^b, \boldsymbol{\varepsilon})$, eqs (1-2) define probability distribution for the couple (\mathbf{x}, \mathbf{y}) , with

$$E(\mathbf{x}) = \mathbf{x}^b, \quad \mathbf{x}' = \mathbf{x} - E(\mathbf{x}) = -\boldsymbol{\zeta}^b$$

$$E(\mathbf{y}) = H\mathbf{x}^b, \quad \mathbf{y}' = \mathbf{y} - E(\mathbf{y}) = \mathbf{y} - H\mathbf{x}^b = \boldsymbol{\varepsilon} - H\boldsymbol{\zeta}^b$$

$\mathbf{d} \equiv \mathbf{y} - H\mathbf{x}^b$ is called the *innovation vector*.

Best Linear Unbiased Estimate (continuation 2)

Apply formulæ for Optimal Interpolation

$$\begin{aligned}\mathbf{x}^a &= \mathbf{x}^b + P^b H^T [HP^b H^T + R]^{-1} (\mathbf{y} - H\mathbf{x}^b) \\ P^a &= P^b - P^b H^T [HP^b H^T + R]^{-1} HP^b\end{aligned}$$

\mathbf{x}^a is the *Best Linear Unbiased Estimate (BLUE)* of x from \mathbf{x}^b and \mathbf{y} .

Equivalent set of formulæ

$$\begin{aligned}\mathbf{x}^a &= \mathbf{x}^b + P^a H^T R^{-1} (\mathbf{y} - H\mathbf{x}^b) \\ [P^a]^{-1} &= [P^b]^{-1} + H^T R^{-1} H\end{aligned}$$

Vector $\mathbf{d} \equiv \mathbf{y} - H\mathbf{x}^b$ is *innovation vector*

Matrix $\mathbf{K} \equiv P^b H^T [HP^b H^T + R]^{-1} = P^a H^T R^{-1}$ is *gain matrix*.

If probability distributions are *globally gaussian*, *BLUE* achieves bayesian estimation, in the sense that $P(\mathbf{x} | \mathbf{x}^b, \mathbf{y}) = \mathcal{N}[\mathbf{x}^a, \mathbf{P}^a]$.

Best Linear Unbiased Estimate (continuation 3)

H can be any linear operator

Example : (scalar) satellite observation

$\mathbf{x} = (x_1, \dots, x_n)^T$ temperature profile

Observation $y = \sum_i h_i x_i + \varepsilon = \mathbf{H}\mathbf{x} + \varepsilon$, $\mathbf{H} = (h_1, \dots, h_n)$, $E(\varepsilon^2) = r$
 Background $\mathbf{x}^b = (x_1^b, \dots, x_n^b)^T$, error covariance matrix $P^b = (p_{ij}^b)$

$$\mathbf{x}^a = \mathbf{x}^b + P^b H^T [HP^b H^T + R]^{-1} (y - H\mathbf{x}^b)$$

$$[HP^b H^T + R]^{-1} (y - H\mathbf{x}^b) = (y - \sum_i h_i x_i^b) / (\sum_{ik} h_i h_k p_{ik}^b + r) \equiv \mu \quad \text{scalar !}$$

- $P^b = p^b \mathbf{I}_n$ $x_i^a = x_i^b + p^b h_i \mu$
- $P^b = \text{diag}(p_{ii}^b)$ $x_i^a = x_i^b + p_{ii}^b h_i \mu$
- General case $x_i^a = x_i^b + \sum_k p_{ik}^b h_k \mu$

Each level i is corrected, not only because of its own contribution to the observation, but because of the contribution of the other levels with which its background error is correlated.

Best Linear Unbiased Estimate (continuation 4)

Variational form of the *BLUE*

BLUE x^a minimizes following scalar *objective function*, defined on state space

$\xi \in \mathcal{S} \rightarrow$

- $$\begin{aligned} \mathcal{J}(\xi) &\equiv (1/2) (x^b - \xi)^T [P^b]^{-1} (x^b - \xi) + (1/2) (y - H\xi)^T R^{-1} (y - H\xi) \\ &\equiv \mathcal{J}_b \quad + \quad \mathcal{J}_o \end{aligned}$$

‘3D-Var’

Can easily, and heuristically, be extended to the case of a nonlinear observation operator H .

Used operationally in USA, Australia, China, ...

Cours à venir

~~Jeudi 6 avril~~

~~Jeudi 13 avril~~

~~Jeudi 20 avril~~

~~Jeudi 11 mai~~

Lundi 29 mai

Jeudi 1 juin

Jeudi 15 juin

Jeudi 22 juin

De 10h00 à 12h30, Salle de la Serre, 5ième étage,
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