

A neural network-based observation operator for weather radar data assimilation







VIPAVA, 09 October 2024



PROJECT ACRONYM 3DVarHNN

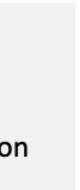
MARCO STEFANELLI







Co-funded by The European Union



OUTLINES

1. INTRODUCTION lacksquare

2. THE 3D-VAR COST FUNCTION

3. METHODOLOGY AND OBJECTIVE OF THE PROJECT

4. CONCLUSIONS

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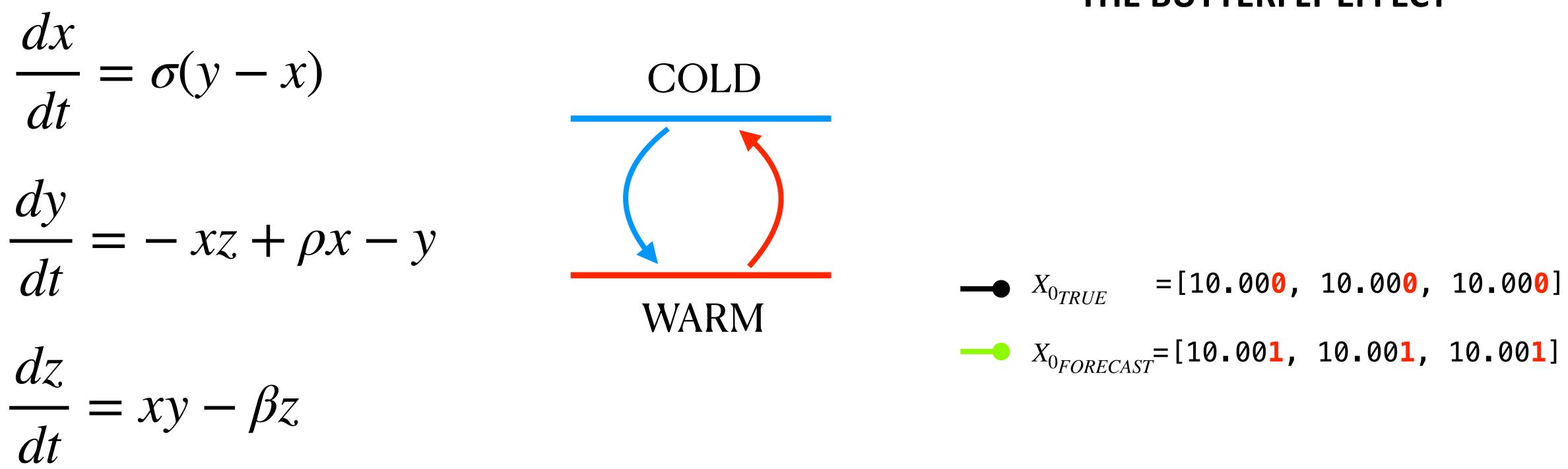
- Deterministic Chaos in Atmosphere
 - Data Assimilation







THE DETERMINISTIC CHAOS THE LORENZ63 MODEL IS A CONVECTIVE SYSTEM OF EQUATIONS IT IS A SIMPLIFICATION OF NAVIER-STOKES EQUATIONS.



Lorenz, Edward N. "Deterministic nonperiodic flow." Journal of atmospheric sciences 20.2 (1963): 130-141.

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THE BUTTERFLY EFFECT

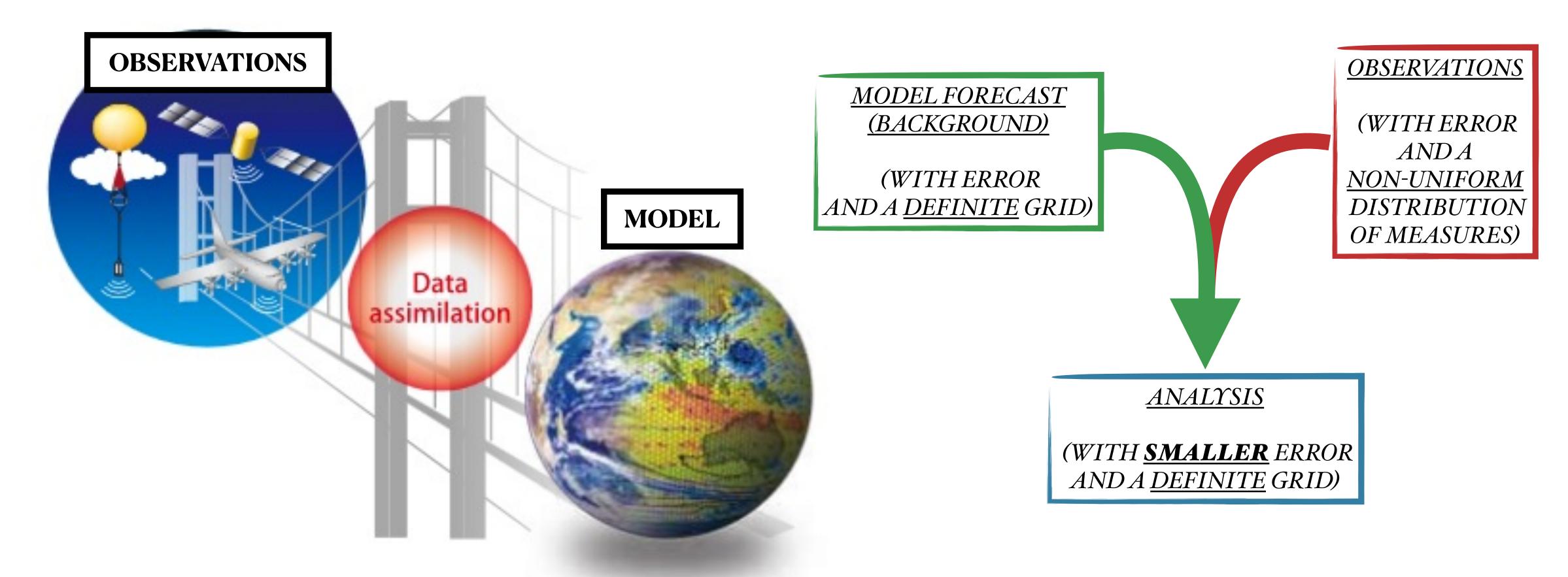








DATAASSIMILATION THE BRIDGE BETWEEN MODEL AND OBSERVATIONS



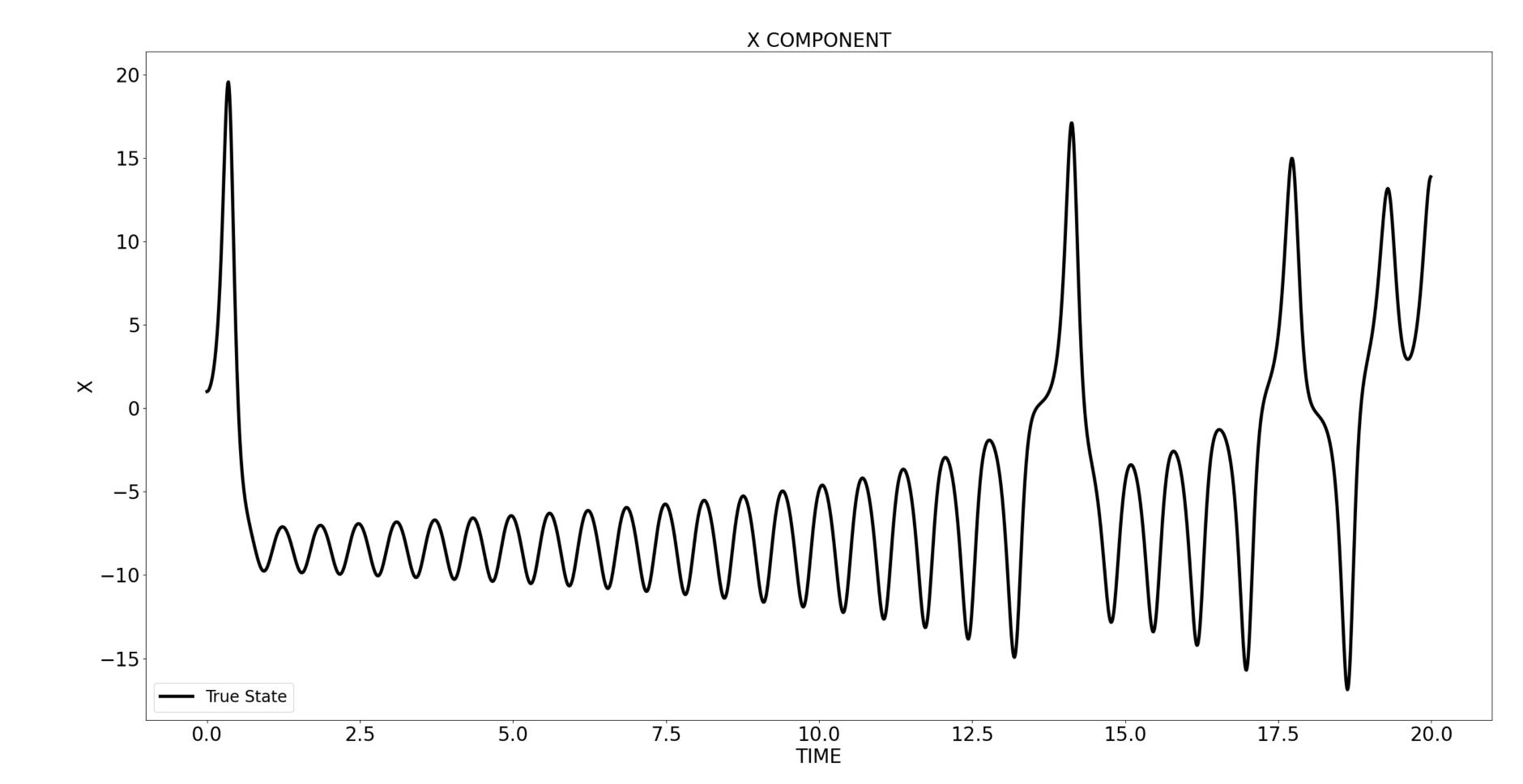
https://www.data-assimilation.riken.jp/en/research/index.html

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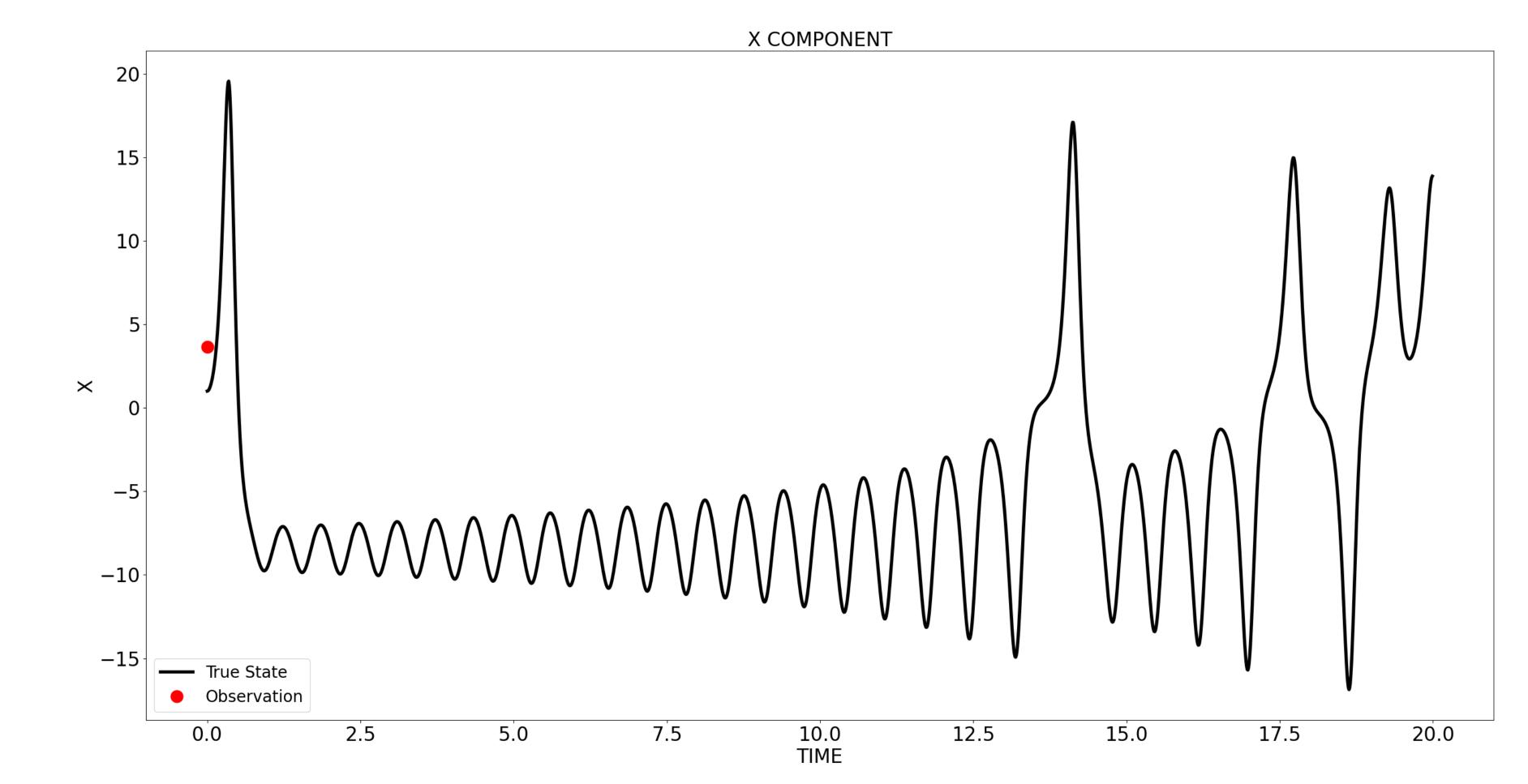




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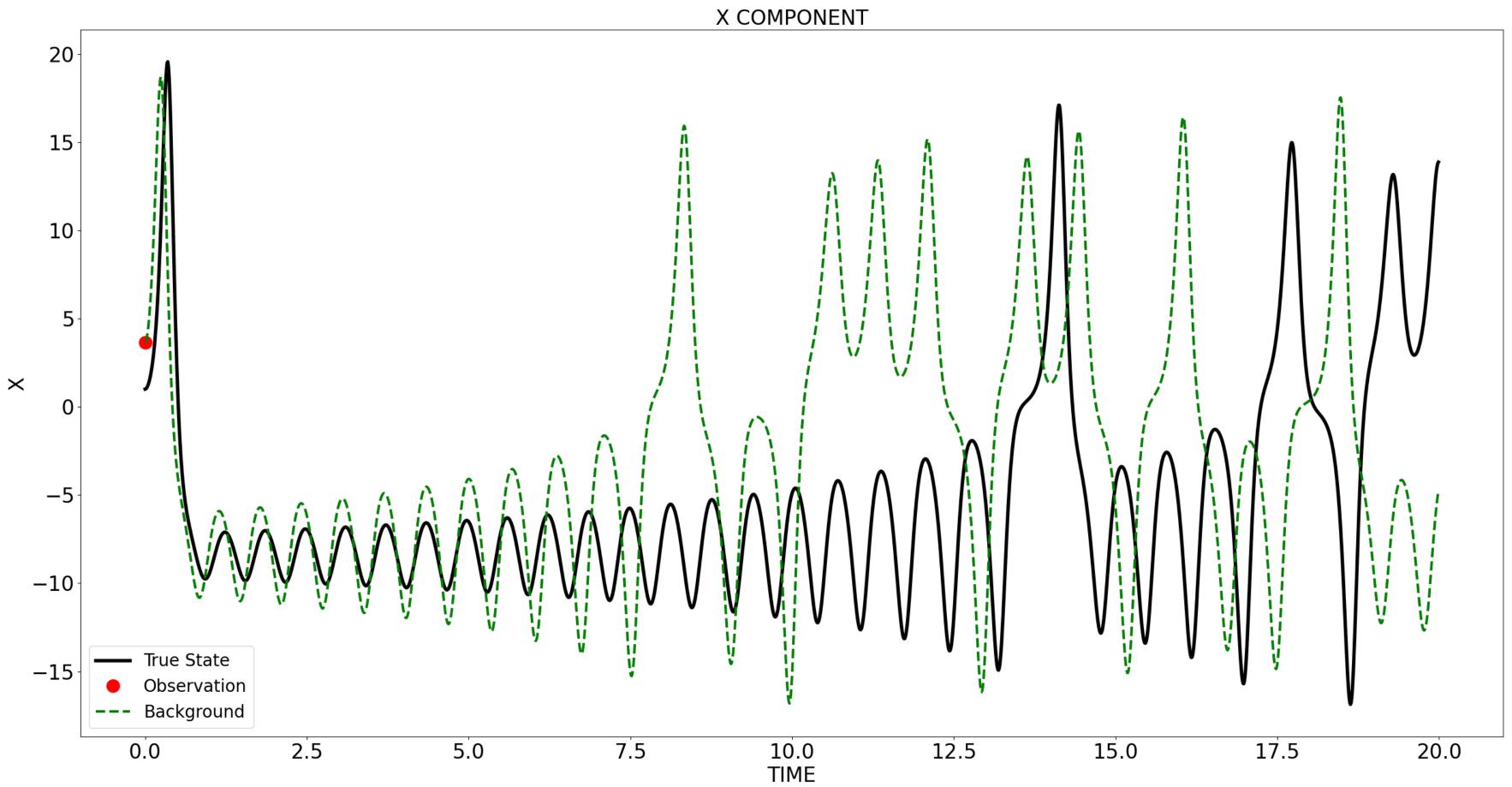






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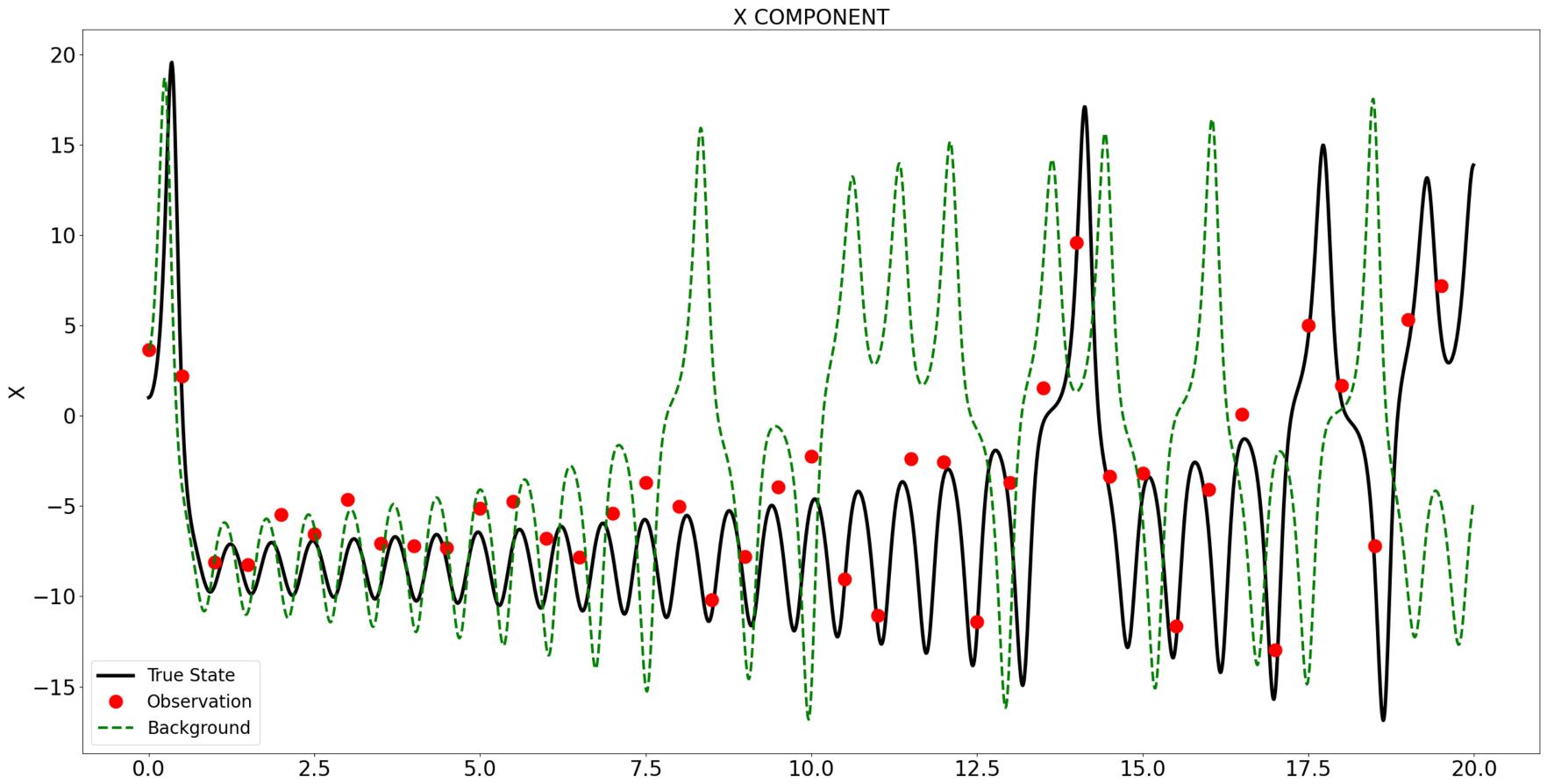




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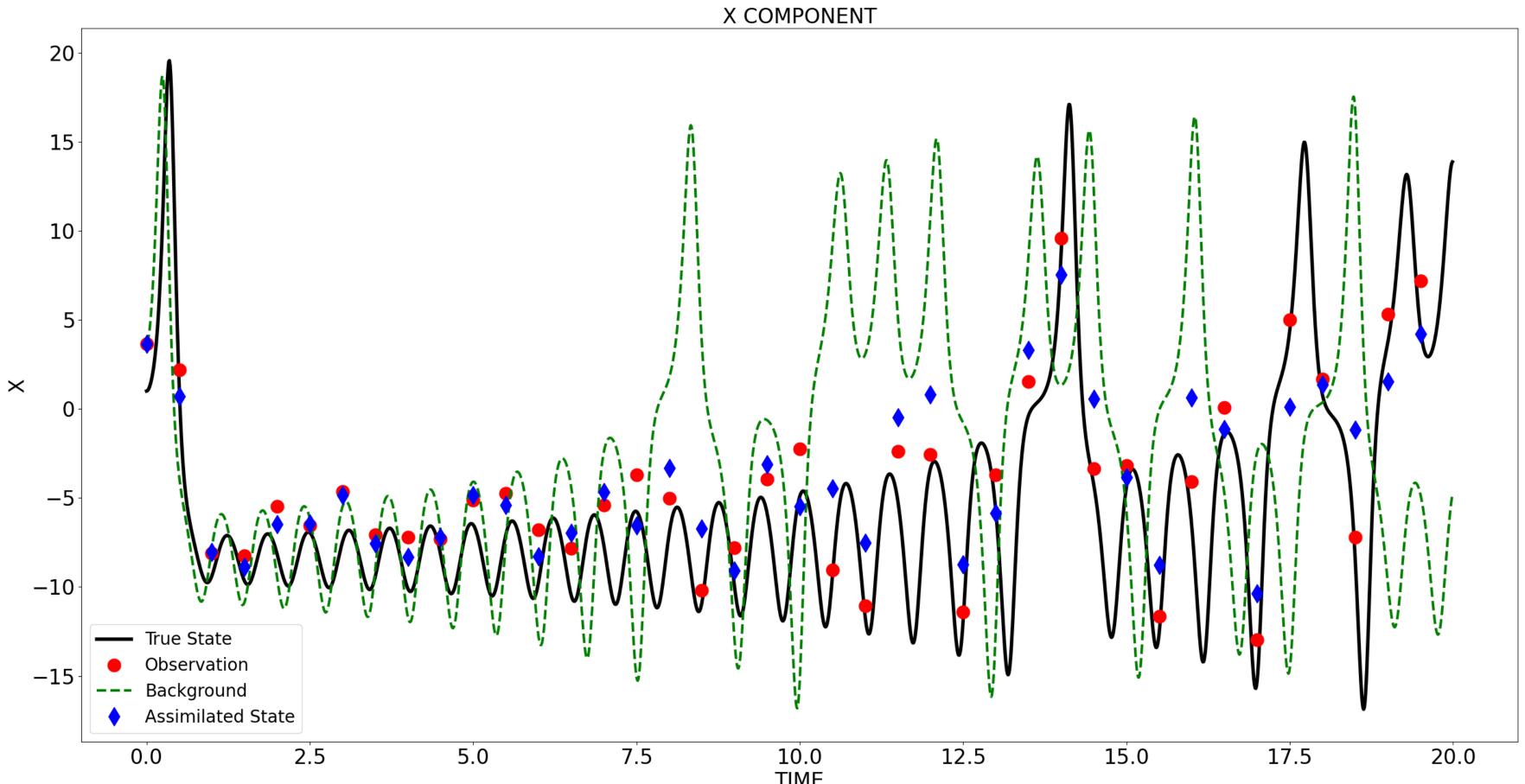
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10.0 TIME







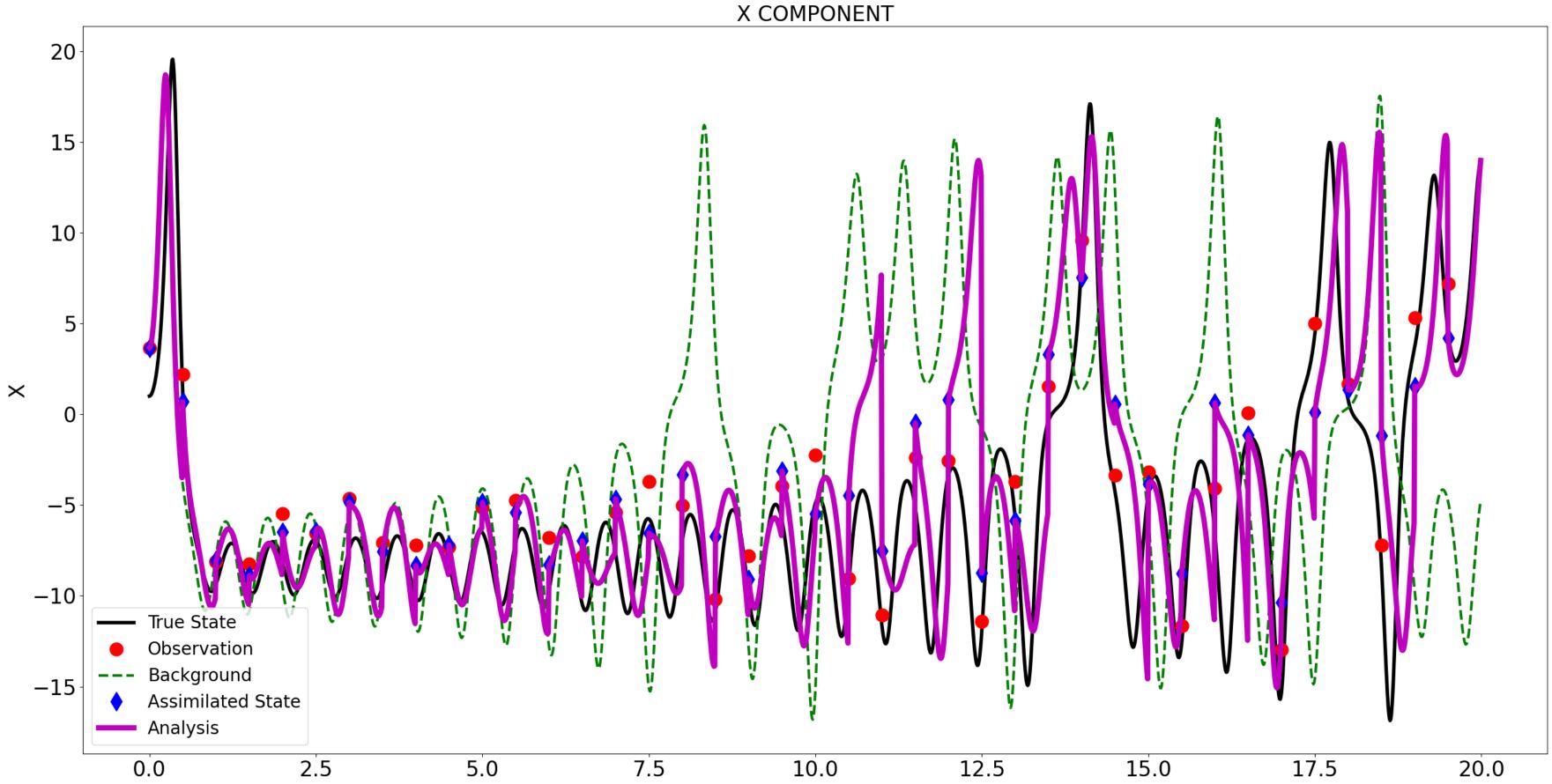


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TIME







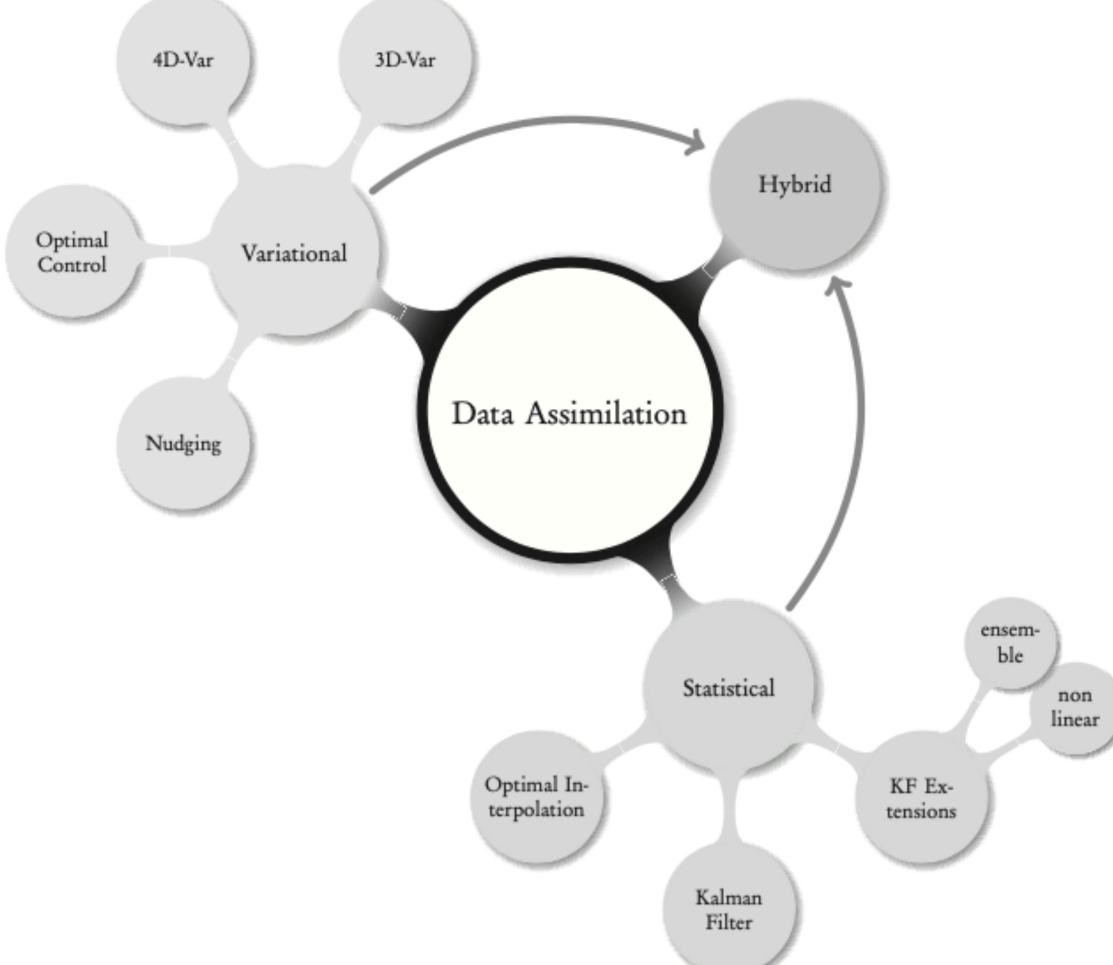
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DIFFERENT METHODOLOGIES OF DATA ASSIMILATION



Data assimilation, methods and applications. Ash et al. 2016

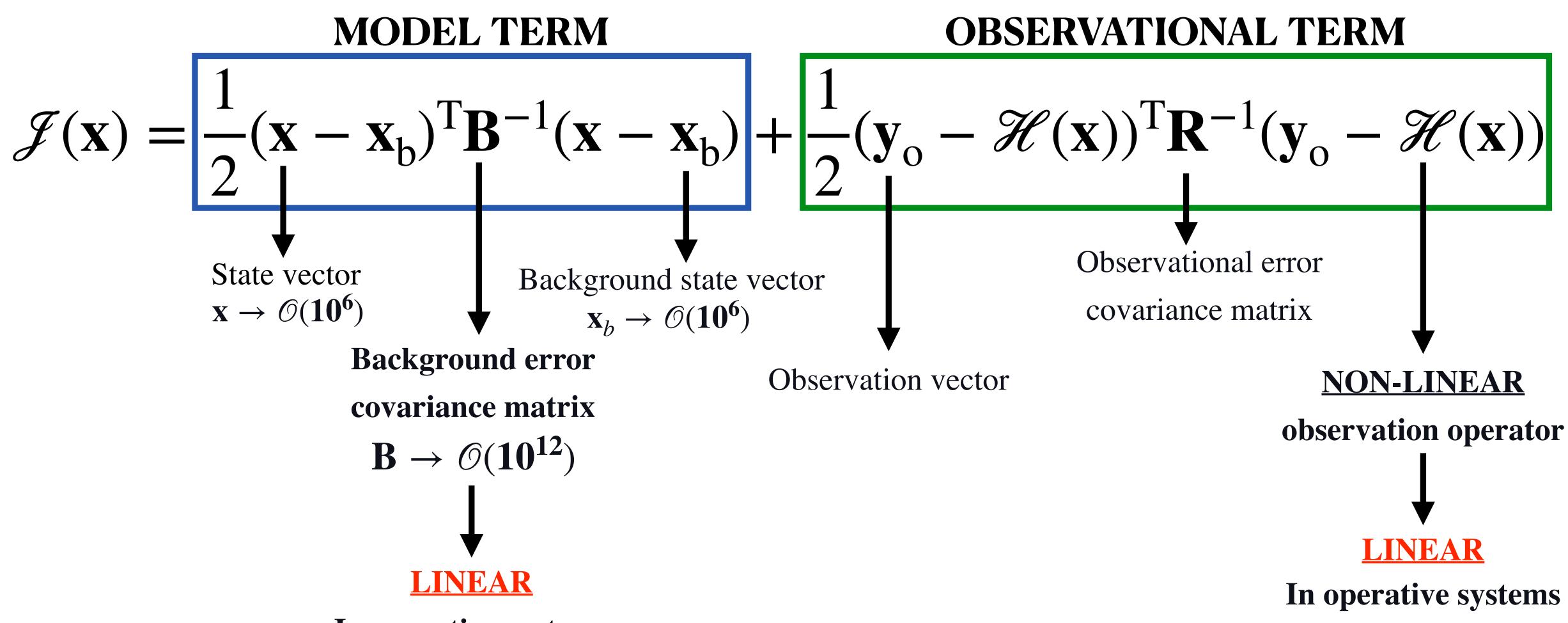
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DATA ASSIMILATION THE 3D-Var COST FUNCTION IN THE PHYSICAL SPACE



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In operative systems









Η

WHY WE WANT TO ASSIMILATE RADAR DATA?

Assimilating radar data is still a challenging task. WHY?

- (e.g. T, q, \mathbf{v}). [1]
- Convective storms have considerably more small-scale variability than other fields. [1]

$$\mathscr{J}(\mathbf{x}) = \frac{1}{2} (\mathbf{x} - \mathbf{x}_{b})^{\mathrm{T}} \mathbf{B}^{-1} (\mathbf{x} - \mathbf{x}_{b}) + \frac{1}{2} (\mathbf{y}_{o} - \mathscr{H}(\mathbf{x}))^{\mathrm{T}} \mathbf{R}^{-1} (\mathbf{y})^{\mathrm{T}} \mathbf{R}^{-1} (\mathbf{y})^{\mathrm$$

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They represent a quantity (reflectivity) with no direct functional correspondence to prognostic model variables



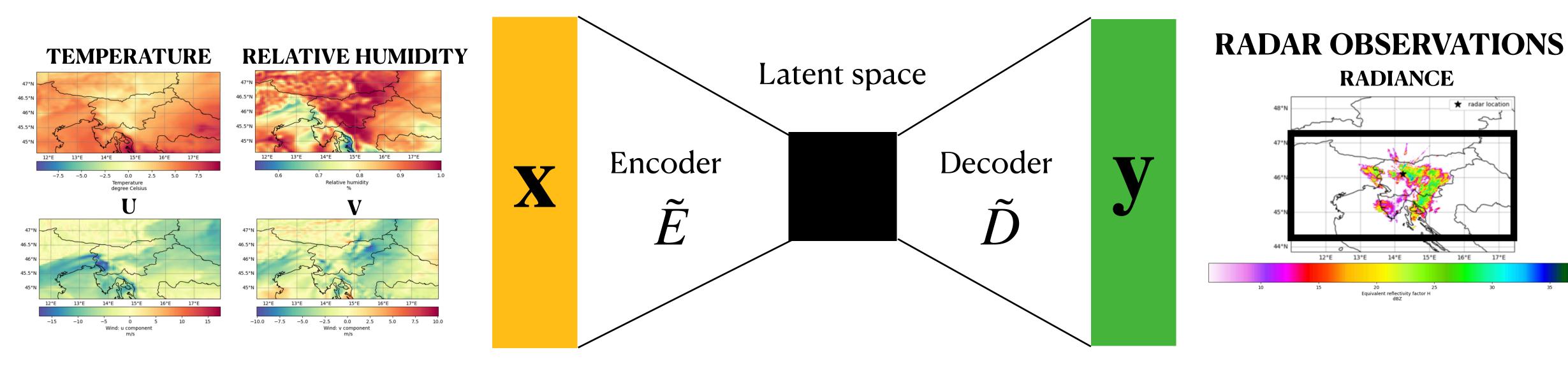






PROJECT METHODOLOGY

ALADIN MODEL VARIABLES



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Generated Model-Equivalent radar reflectivities

Build an encoder-decoder neural network with input model data and output reflectivity data.

$$(\tilde{E}(\mathbf{x})) = \mathscr{H}(\mathbf{x})$$

Non-linear Observation Operator

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★ radar location

16°E

SMASH

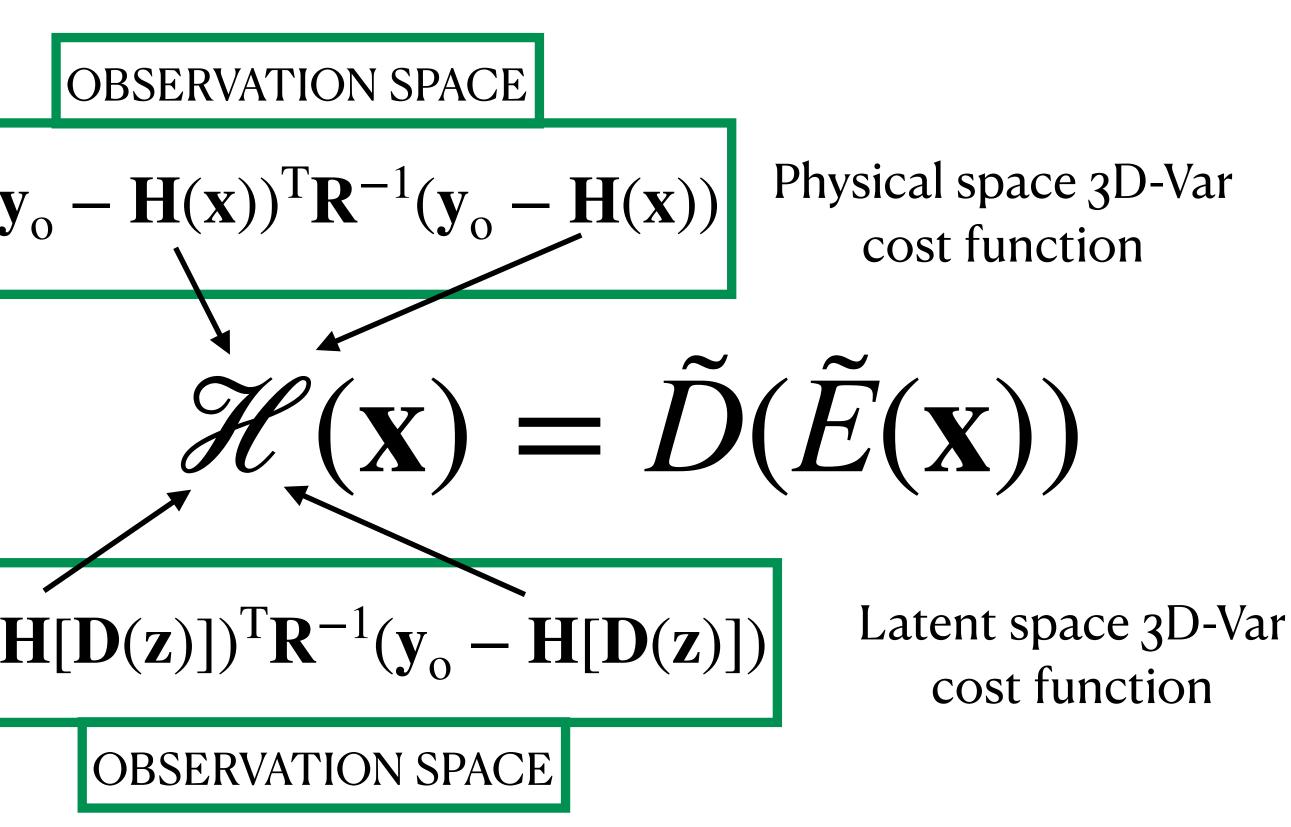
RESULTS APPLICATIONS

PHYSICAL SPACE
$$\mathcal{J}(\mathbf{x}) = \frac{1}{2} (\mathbf{x} - \mathbf{x}_b)^{\mathrm{T}} \mathbf{B}^{-1} (\mathbf{x} - \mathbf{x}_b) + \frac{1}{2} (\mathbf{y})^{\mathrm{T}} \mathbf{B}^{-1} (\mathbf{x} - \mathbf{x}_b) + \frac{1}{2} (\mathbf{x} - \mathbf{x}_b) + \frac{1}{2} (\mathbf{x} - \mathbf{x}_b) + \frac{1}{$$

$$\mathscr{J}(\mathbf{z}) = \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{y}_o - \mathbf{B}_z)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{y}_o - \mathbf{B}_z)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{y}_o - \mathbf{B}_z)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z} - \mathbf{z}_b)^{\mathrm{T}} \mathbf{B}_z^{-1} (\mathbf{z} - \mathbf{z}_b) + \frac{1}{2} (\mathbf{z$$

Melnic and Zaplotnic; Neural-Network Data Assimilation using Variational Autoencoder. (2023)

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ADDED VALUE OF THE PROJECT

Definition of a non-linear observation operator to assimilate radar data and a possible improvement of the NWP skill in forecasting **CONVECTIVE STORMS**

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HEAVY PRECIPITATIONS IN THE CLIMATE CHANGE ERA: MORE FREQUENT & MORE INTENSE

'Nature fights back': Slovenia's worst floods kill six

By Fedja Grulovic

August 7, 2023 3:44 PM GMT+2 · Updated a year ago



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[5/5] A view of a damaged building in a flooded area, following heavy rains, in Prevalje, Slovenia August 6, 2023. REUTERS/Fedja Grulovic/File photo Purchase Licensing Rights

Flash floods and landslides hit parts of Bosnia, killing at least 16

() Friday 4 October 2024 16:35, UK



Search and rescue teams look for people in the flooded houses in Jablanica, Bosnia. Pic: AP



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CLIMATE

Catastrophic floods in Italy force thousands of people to leave their homes

PUBLISHED THU, MAY 18 2023-1:19 PM EDT



In this aerial picture, flooded streets caused by heavy rains across Italy's northern Emilia Romagna region, on May 18, 2023 in Lugo Italy

Antonio Masiello | Getty Images

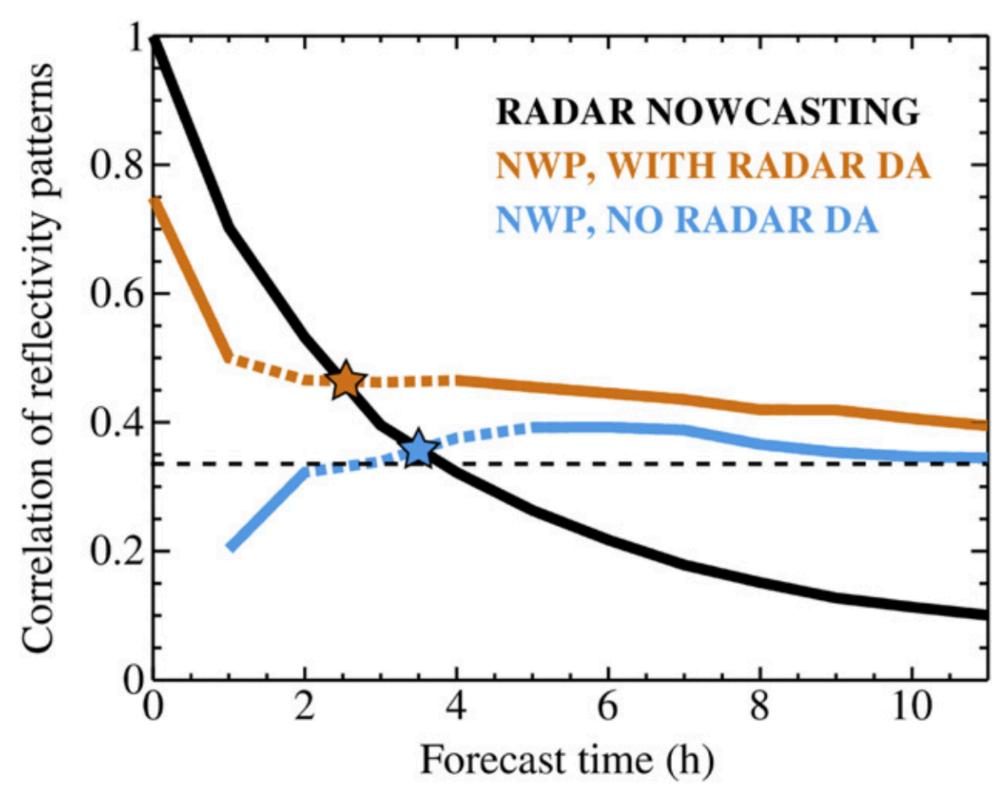
Thank you!







WHY WE WANT TO ASSIMILATE RADAR DATA? RADAR IS OUR BEST INSTRUMENT TO MONITOR AND STUDY STORMS



Fabry, F., & Meunier, V. (2020). Why are radar data so difficult to assimilate skillfully? Monthly Weather Review, 148(7), 2819-2836.

Attempts to assimilate radar data showed poor improvements in forecasting precipitation patterns.

- Skill of NWP aided by radar data assimilation drops very rapidly in the first forecast hour
- Extrapolation methods (NOWCASTING) beat ulletnumerical forecasting of precipitation patterns in the first 2 or 3 h



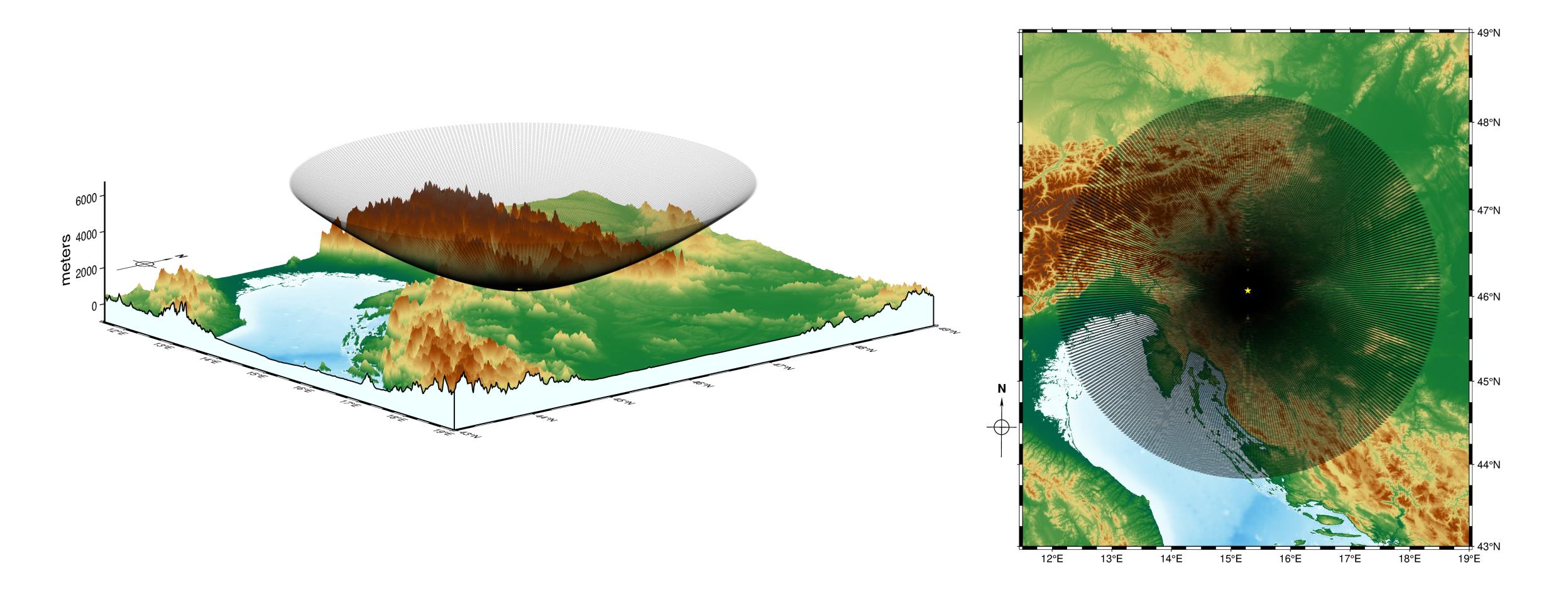
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18

SMASH

RADAR DATA STRUCTURE OF THE FIRST ELEVATION ANGLE **0.5 deg**









ALADIN PRESSURE LEVELS AND RADAR DATA AT DIFFERENT ELEVATION ANGLES

RADAR CONES AND ALADIN PRESSURE LEVELS

