

THE UNIVERSITY OF READING
DEPARTMENTS OF MATHEMATICS AND METEOROLOGY

4D-Var for high resolution,

Abstract

z do o e e e e e e o en c ed y oc ed con ec e c e e e e
e e e oc nd econo c p c o c e en e c e ed o n need n
n e c e e p ed c on o p o e e cc cy o con ec e c e o ec n
M ny ope on cen e o nd e o d e de e op n o ec n o de p
e o on do n o c e e o on o do n n o on
con ec e c e o e ene y e e p e en ed
n cond on o n e c o ec n o de e p o ded n d
on e ed c c o ne o e on c en e e o e o p e c
e o e e d e o n co p e po e e y e o on o de c n on y
co e e ed e do n e n e e y e p e n o n p e en n e
o p e e en e c e e on e n do n o o de
p o n e d o n on e ed e o de LAM c p e
o e e nd e c e nc d n en e c e on e n LAM do n
o ne e d e en c e e e ed n LAM d o n e ne
e ed e do n e ne d ec on d on o de nd p e en o
d en on on d o n c e e e e d c e e o e
ne n o o n e e c e en e c p ed y d o n
e e e e o on o e on LAM d o n e
o cc e y e p e en e c e o e e c nno c p e e c y
d e o e o co n o e o nd y cond on e de on e e o o
e o nd y cond on e o n n e o on o LAM c e e o
o en e e e o e en e c e on e n LAM do n e
ed on o o e en e e e o y o e n o n en ed on o
e on e e con ned y LAM pec n n o ed e e de e op
ne e ed o p o n e o en e n LAM
n n n e cc cy n e c e c e ed y e e o on

Declaration

I, _____, do hereby declare that the above information is true and correct to the best of my knowledge and belief.

Signature _____

Acknowledgements

I would like to thank my co-authors, Dr. [Name] and Dr. [Name], for their support and guidance throughout the project. I also thank my family, especially my mother, for their love and encouragement. Finally, I thank my friends for their support and encouragement.

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Manipulating scales in a 4D Var analysis using the background error covariance matrix

Journal of Climate, 2006, 19, 1771–1784

7 Mode o p t o d e e n p e o o n n d
e o c o p e d o n y c o o n

7 e c o n o d e n c c o n o d p o n c e

7 e c o n o d e n c c o n o p e c c e

Mode o p n d p o e p e c t e n u r x j
n n x j n n x j

7 Mode o p n d p o e p e c d d e o o n n
d o e u r x j n n x j n n x j

Mode o p n d p o e p e c t c o p o n o L A M
n d d o n

Mode o p n d p o e p e c d d e o o n n
d o c o p o n o L A M n d d o n

e e n e e e n e u x j n n x j e n e e d
e o o n e d c o p e d o p y n e p o n o e e o o n e
e

Mode o p n d p o e p e c t c o p n e n y e n
e e d e e o o n o n p e n n d L A M d o n

7 Mode o p n d p o e p e c d d e o o n n
d o c o p n e n y e n e e d e e e o o n o n
p e n n d L A M d o n

Mode o p n d p o e p e c t e n u r x j
n n x j n n x j n n x j

Mode o p n d p o e p e c d d e o o n n
d o e u r x j n n x j n n x j n n x j
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Mode o p n d p o e p e c t e n u r x j
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7

Mode o p n d p o e p e c e n d o o n n d o
e u r x j n n x j / n n x j / n n x j
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7 Mode o p n d p o e p e c t e n u r x j
n n x j n n x j n n x j n n x j

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	Mode o p	en e	e	on		
	Co ₁ p	n o ce o x ^b o	n e e	1p e		7
7	Co ₁ p	n o ce o x ^b o	n e e	1p e	p e e	7
	Co ₁ p	n o ce o x ^b o	ne e e	1p e		77
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	Mode o p	nd po e pec	o c e	α ¹		
	Mode o p	nd po e pec	o c e	β ¹		
7	Mode o p	t o 0 ¹	A α	nd β		
	o n	po e pec 1 t	o 0 ¹	A α	nd β	
	o n	po e pec 1 t	o 0 ¹	A α	nd β	coe
	p o k	,..., nd k	,...,7			
	Mode o p	t o 0 ¹	A B	nd γ		
	o n	po e pec 1 t	o 0 ¹	A B	nd γ	7
7	o n	po e pec 1 t	o 0 ¹	A B	nd γ	coe
	p o k	,..., nd k	,...,7			
	o n	po e pec 1 t	o μ v ω	nd η		
	o n	po e pec 1 t	o μ v ω	nd η	coe	
	p o k	,..., nd k	,...,7			7

Acronyms

N		N e c e p e d c o n
LAM		L e d e o d e
LBC		L e o n d y c o n d o n
	d e n o n o n d	e n o n
	d e n o n o n d	e n o n
	n e	n e
n	n e e	n e
	c e e o e n o	
	o e n o	

Data Assimilation Notation

x	e	ec	o	
x^a	n	y	ec	o
x^t	e	e	ec	o
x^b	c	o	nd	e p o e $\frac{1}{2}$ e
y	o	e	on	ec o
h	o	e	on	ope o
H	ne	on	o o e	on ope o h

Model Notation

u	 type e e
x^P	 en p coo d n e
x^L	LAM p coo d n e
t	 e
c	Ad ec on e oc y
σ	 on con n
x^P	 en d p c n
t^P	 en  ep
x^L	LAM d p c n
t^L	LAM  ep
N	N  e o p en dpo n
M	N  e o LAM dpo n
T	N  e o p en  ode  ep n   on ndo
S	N  e o LAM  ep n   on ndo
h	o o LAM o p en d p ce
τ	o o LAM o p en  ep
D	N  e o p en  ode d p ce co e ed y LAM
B	 en dpo n co e pond n o  LAM o nd y
B₂	 en dpo n co e pond n o econd LAM o nd y
b	d  e zone

Chapter 1

Introduction

The ultimate problem in meteorology [18, p. 6].

modellen een edodec e poe oec n e
C p . Acco d n o B e ne o p od ce e e o ec

1.1 Motivation

En oec n e e e e ny c e ocon de e e oec n
ynop c c e p eno en o o de o o e Mo o e nd o p e e
e een on e e p e on e ynop c c e A en ey e e
oec n o e oc ed p eno en occ on e o c e o con ec e c e
o o de e o e e nd ed ne on nd o nd e
e o c e e e en nd d nde o occ on con ec e c e

z do o e e e o en c ed y con ec e c e e Con ec
e o o p od ce o o o o d n e e e pe enced n
e e dn c e o ood n e o e e e on e e e n o

7. en ape ec o e on nd no c o nd e LAM d
 on c nno c p e e c y d e o e o n od ced o o
 LBC

o n od ced o o LBC e d e ence n e o on e een
 nd LAM c e LAM d on o e e o o
 en e

n LAM d on e en c e on e n do n o
 LAM e ed on o o en e o

Chapter 2

Data Assimilation

do not see the connection between the two
processes

node one is connected to the other by the
edge connecting the two nodes. The
other nodes in the network are not
connected to the two nodes.

An N node is a node in the network
that is connected to the other nodes
by the edge connecting the two nodes. The
other nodes in the network are not
connected to the two nodes.

Many types of nodes are connected to the
other nodes in the network. The
other nodes in the network are not
connected to the two nodes.

2.1 Types of data assimilation

The many types of nodes are connected to the
other nodes in the network. The
other nodes in the network are not
connected to the two nodes.

2.1.2 Variational schemes

In this section we consider the problem of finding the minimum of a functional $J(x)$ over a set S . The functional $J(x)$ is defined as the integral of a function $f(x)$ over a domain Ω . The set S is defined as the set of functions x that satisfy the boundary conditions. The problem is to find the function x^* that minimizes $J(x)$ over S .

A necessary condition for a function x^* to be a minimum is that it must satisfy the Euler-Lagrange equation. This equation is derived from the first variation of the functional $J(x)$.

$$J'(x) = 0$$

dependence between the continuous and discrete components of the dependence is one of the main challenges in the design of the Kalman filter. The Kalman filter is a recursive algorithm that estimates the state of a system over time. It is based on the assumption that the system is linear and the noise is Gaussian. The Kalman filter consists of two main steps: prediction and update. The prediction step uses the previous state estimate and the system model to predict the current state. The update step uses the current measurement and the prediction to update the state estimate. The Kalman filter is widely used in many applications, such as navigation, robotics, and control systems.

2.1.3 The Kalman Filter

Consider a system with state $\mathbf{x}_k$ and measurement $\mathbf{y}_k$. The state evolves according to the discrete-time state equation:
$$\mathbf{x}_k = \mathbf{M}_{k-1} \mathbf{x}_{k-1} + \mathbf{w}_k$$
where $\mathbf{M}_{k-1}$ is the state transition matrix and $\mathbf{w}_k$ is the process noise. The measurement is given by:
$$\mathbf{y}_k = \mathbf{H}_k \mathbf{x}_k + \mathbf{v}_k$$
where $\mathbf{H}_k$ is the observation matrix and $\mathbf{v}_k$ is the measurement noise. The Kalman filter estimates the state $\mathbf{x}_k$ using the measurements $\mathbf{y}_k$ and the previous state estimate $\hat{\mathbf{x}}_{k-1}$.

The Kalman filter consists of two main steps: prediction and update. The prediction step uses the previous state estimate and the system model to predict the current state. The update step uses the current measurement and the prediction to update the state estimate.

$$\mathbf{x}_k^f = \mathbf{M}_{k-1} \mathbf{x}_{k-1}^a, \quad (2.1.3.1)$$

and the covariance matrix is updated as:

$$\mathbf{P}_k^f = \mathbf{M}_{k-1} \mathbf{P}_{k-1}^a \mathbf{M}_{k-1}^T, \quad (2.1.3.2)$$

where $\mathbf{M}_k$ is the state transition matrix, $\mathbf{t}_k$ is the time step, and $\mathbf{P}_k$ is the covariance matrix. The Kalman filter also uses the measurement $\mathbf{y}_k$ to update the state estimate. The update step uses the current measurement and the prediction to update the state estimate. The Kalman filter is widely used in many applications, such as navigation, robotics, and control systems.

$$\mathbf{K}_k = \mathbf{P}_k^f \mathbf{H}_k^T (\mathbf{H}_k \mathbf{P}_k^f \mathbf{H}_k^T + \mathbf{R}_k)^{-1}, \quad (2.1.3.3)$$

where $\mathbf{H}_k$ is the observation matrix and $\mathbf{R}_k$ is the measurement noise covariance matrix.

$$\mathbf{x}_k^a = \mathbf{x}_k^f + \mathbf{K}_k (\mathbf{y}_k - \mathbf{H}_k \mathbf{x}_k^f), \quad (2.1.3.4)$$

and the covariance matrix is updated as:

$$\mathbf{P}_k^a = \mathbf{I} - \mathbf{K}_k \mathbf{H}_k \mathbf{P}_k^f, \quad (2.1.3.5)$$

Bo
nd
ene
o
n e o ed e o co nce
o d n e o
d nce c o nd e o co nce n
e o co nce o ec ep e o co nce o ec p o de o dependen
c o nd e o co nce
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n e
n con n co nce
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A ency _e o on Me Q ce _ode c en y n
_ _o _o n o nd e e e dy p n p ed y
Me eo nce o ed _e o on _ed e _ _ _ d

on ∇ e ∇ con ∇ ne on ∇ ne ne on ∇ ∇ c
 d n ∇ o ∇ t o t e ∇ d o n e on

$$\lambda_{+1} \qquad \nabla$$

$$\lambda_k - \mathbf{M}_k^\top \lambda_{k+1} - \mathbf{H}_k^\top \mathbf{R}_k^{-1} \mathbf{y}_k - \mathbf{h}_k \mathbf{x}_k, \quad k = \mathcal{T}, \dots, . \qquad \nabla$$

∇ d en o $\mathbf{J}_0$ ∇ n ∇ e ∇ n en y

$$\nabla \mathbf{J}_0 \mathbf{x}_0 = -\lambda_0. \qquad \nabla$$

∇ c n no e ed n n e e e on ∇ e e ∇ d en o $\mathbf{J}$ o e
 c c ed $\mathbf{M}$ no n ∇ o d ne ∇ o de nd $\mathbf{M}^\top$ ∇ d o n ∇ o de

on ∇ o nd n L n e ∇ p e ∇ ∇ e e o nd n
 ne e ∇ ∇ n n ec on ∇

∇ c c o on pp o c ∇ o o ∇ n ∇ n n n nde
 nd n ∇ con c on o ∇ con ned ∇ n ∇ on e ∇ p n

$$\begin{aligned} \mathbf{J} \mathbf{x}_0 &= \mathbf{x}_0 - \mathbf{x}^b \mathbf{B}^{-1} \mathbf{x}_0 - \mathbf{x}^b \\ &= \mathbf{I} \mathbf{x}_0 - \mathbf{H}_k \mathbf{x}_k \mathbf{R}_k^{-1} \mathbf{y}_k - \mathbf{H}_k \mathbf{x}_k, \end{aligned} \quad (7)$$

def $\mathbf{J}_b = \mathbf{J}_0,$

nd ~~de~~ con n

$$\mathbf{x}_k = \mathbf{M}_{k-1} \mathbf{x}_{k-1}.$$

$\mathbf{J}_b$ defined on $\mathcal{C}$ and $\mathbf{J}_0$ defined on $\mathcal{C}_0$

2.3.1 Minimisation of the cost function J

o n e co nc on e e e n on o o e c ce
nc de Ne on o con e den ed de c p on o
e e ed c n e o nd n o ec on o e pe nd e
e o e no de c ed e o e e e ype o den de cen o
e e e o J nd den J o e c c ed e c e on nd e
e o e need o con de e c n e e ed

The on o co nc on e ey o d y p y c c n
 e on 7 7 n J b c n e c c e d d e c y o c c e J o e 1 1 p y
 e o n en ne 1 o d e M k o e o e o o on o d n 1 e c n en
 c c e nd o e

$$\mathbf{d}_k = \mathbf{R}_k^{-1} (\mathbf{y}_k - \mathbf{H}_k \mathbf{x}_k), \quad \triangleright$$

$\mathbf{d}_k$ e no n $\mathbf{d}_1$ ed dep e $\mathbf{d}$ e dep e c n $\mathbf{d}$ e ed
 o c c e $\mathbf{J}_0$ e e o con on

$$\mathbf{J}_0 \mathbf{x} = \sum_k \mathbf{J}_{0k} \mathbf{x}, \quad \triangleright \triangleright$$

Q e

$$\mathbf{J}_{0k} \mathbf{x} = \mathbf{y}_k - \mathbf{H}_k \mathbf{x}_k^T \mathbf{d}_k. \quad \gg$$

the on o d en c n o e done n o p d en o $\mathbf{J}_b$ c n
 upy e o nd y c c n $\nabla \mathbf{J}_b$ d ec y

$$\nabla \mathbf{J}_b = \mathbf{B}^{-1} \mathbf{x}_0 - \mathbf{x}_b . \quad \gg$$

o c c e $\nabla \mathbf{J}_0$ d ec y o d e co up on y ne e o d e e $\mathbf{N}$
 o d ude n d on o $\nabla \mathbf{J}_0$ o e c c ed a one don
 ude n e need o c o e

$$\begin{aligned} \nabla \mathbf{J}_0 \mathbf{x} &= \sum_k \nabla \mathbf{J}_{0k} \mathbf{x} , \\ &= \sum_k \mathbf{M}_1^T \dots \mathbf{M}_k^T \mathbf{H}_k^T \mathbf{d}_k , \\ &= \mathbf{H}_0^T \mathbf{d}_0 + \mathbf{M}_1^T \mathbf{H}_1^T \mathbf{d}_1 + \mathbf{M}_2^T \mathbf{H}_2^T \mathbf{d}_2 \\ &\quad + \mathbf{M}_3^T \mathbf{H}_3^T \mathbf{d}_3 + \dots + \mathbf{M}^T \mathbf{H}^T \mathbf{d} . \quad \gg \end{aligned}$$

on $\gg$ c n no e c c ed o u a o e y n n d on
 e λ o ze o n u λ_{+1} ne on $\gg$ e en ep
 c d u a u ep e c ep dd n o c n e u $\mathbf{H}_k^T \mathbf{d}_k$ o λ_k
 e o e p p y n d on ude o e λ_k - ence e on $\gg$ eco u $\gg$

$$\nabla \mathbf{J}_0 \mathbf{x} = -\lambda . \quad \gg$$

d en o $\mathbf{J}_0$ a een o nd e n ne e e e on $\gg$
 u u o nd n ec on $\gg$ e on $\gg$ de ed y u u o
 L n e u p e

e e d on ude d ed n po e o n en ne ude e $\mathbf{M}^T$
 Ope on y e e d on no con c ed e p c y o u n po e o
 n en ne ude u d on ude nd e ed no con de ed
 n e ne ec on

2.3.2 The adjoint model

Ope on y d c e e ude ne ed o e n en ne ude nd en
 d c e e d on e on e con c ed o u d c e e ne ed e on
 d on de ed d ec y o u n en ne ude code n n o u c
 don u u d $\gg$

o f e e e c n o e e e o o d c e e n e n e e o n o
 nd e n p o e e o e e z e o e y e o e e d n e
 p e e c y e e e o p y n p o e e M o e n e e d o n o
 e e done n o c e e C a p e

Once e d o n c o n c e d n e e e e d e e e o d e e n p e c
 e e e e e e d n d e e e d o n e n e p e e e d

The Adjoint test

e n e d o n e o n e e e e n d e e d d e c y o e e o d e c o d e e d o n
 c o d e n e e e e e d o e y p o d c n e c o e c d o n o d o e e e
 e d e n o n

$$\langle \mathbf{A}\mathbf{b}, \mathbf{c} \rangle = \langle \mathbf{b}, \mathbf{A}^T \mathbf{c} \rangle, \quad \gg$$

e e **A** n e o p e o **A**^T d o n **b** n d **c** e e c o n d e c e
 ..., ... d e n e n n e p o d c

e e e o o e o d e **M** n d d o n **M**^T e c n e e o n e
 y p p y n e o d e o e n c o n d o n **δx**₀ o p o d c e n e e n
 p p y n e d o n o n e

e d o n c o e c e e d e

$$\langle \mathbf{M} \delta \mathbf{x}_0, \mathbf{M} \delta \mathbf{x}_0 \rangle = \langle \delta \mathbf{x}_0, \mathbf{M}^T \mathbf{M} \delta \mathbf{x}_0 \rangle.$$

The Gradient test

e e e y e e d o n p o d c e e c o e c d e n o e c o n c o n o
 d o e e e d e n e e e d e d y e e d o e d o n o d e
 o e p e

A y o e p n o n o e c o n c o n **J** e

$$\mathbf{J} \mathbf{x} + \alpha \overline{\delta \mathbf{x}} = \mathbf{J} \mathbf{x} + \alpha \overline{\delta \mathbf{x}}^T \nabla \mathbf{J} \mathbf{x} + \mathcal{O}(\alpha), \quad \gg$$

e e **α** e c n d **δx** e c o o n e n e o e c n e

needed of the function of α

$$\varphi(\alpha) = \frac{\mathbf{J}(\mathbf{x}) - \alpha \overline{\delta \mathbf{x}} - \mathbf{J}(\mathbf{x})}{\alpha \overline{\delta \mathbf{x}}^T \nabla \mathbf{J}(\mathbf{x})} = O(\alpha).$$

n ec on 7 e de on ed o o n e co nc on e pec o **X**
o e e / e ed e e p o e o e e en n nd n e n e **B**
o N (e p y ne e e **B** yp c y o O o
o e co e p o e co nc on n e d po ed n e o d e en con o
e y e n o con o e n o 7 e

Chapter 3

The discrete Fourier transform

In this chapter we introduce the discrete Fourier transform (DFT) and its properties. The DFT is a discrete version of the Fourier transform, which is a continuous transform. The DFT is used to analyze discrete-time signals and systems. It is a fundamental tool in digital signal processing.

3.1 Definition

The N -point discrete Fourier transform (DFT) of a discrete-time signal $x[n]$ is defined as

$$X[k] = \sum_{n=0}^{N-1} x[n] e^{-j2\pi kn/N} \quad \text{if } 0 \leq k < N, k \in \mathbb{Z}$$

$$X[k] = 0 \quad \text{otherwise,}$$

where ξ

The discrete-time Fourier transform (DTFT) of a discrete-time signal $x[n]$ is defined as

$$\text{DFT } X[k] = \sum_{n=0}^{N-1} x[n] e^{-j 2\pi k n / N}, \quad k = 0, 1, \dots, N-1,$$

where k is the frequency index and N is the number of samples.

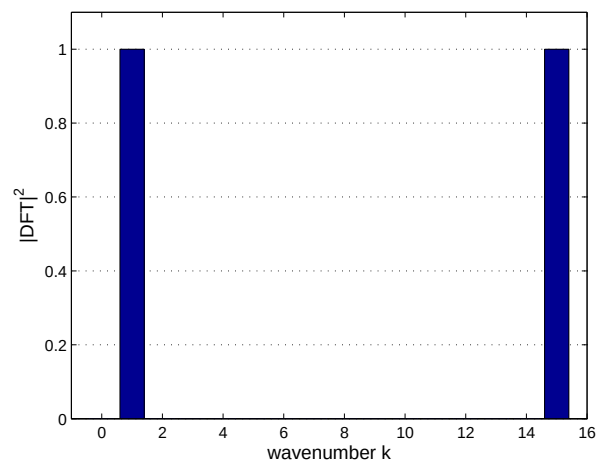


Figure 3.1: The power spectrum of $\sin(\xi_j)$, scaled by the factor $2/N$.

$$\hat{f}_k = \frac{1}{N} \sum_{j=0}^{N-1} e^{-i\xi_j(k-\kappa)} + \frac{1}{N} \sum_{j=0}^{N-1} e^{-i\xi_j(k+\kappa)}.$$

node of the tree on the left is the complex conjugate component

e $\frac{1}{N}$ po e pec $\frac{1}{N}$ o n ξ_j on $\frac{1}{N}$ do $\frac{1}{N}$ n x ,
 e $\xi_j = \pi x_j$, , $N - x_j = j/N$ nd N

By e n k ne on e e e e e po e pec $\frac{1}{N}$
 n ξ_j po ed n e e e e ap de k nd $k = N -$ nd ze o
 e ey e e e By ppy n e c n co $\frac{1}{N}$ oe on e o o n n
 ap de o one

o $\frac{1}{N}$ e e e e e e c n e n o e e e e ne o e po e pec $\frac{1}{N}$
 e po e pec $\frac{1}{N}$ o de e e ad o o e e e e e o e e coe c en
 n n e y

e e e $\frac{1}{N}$ ny no n po e e o e e nd de c p on o e e c n e o nd
 n e c on nd $\frac{1}{N}$ p nd $\frac{1}{N}$ p on o e e e po e
 e o e po e e nd e e e $\frac{1}{N}$ e e e e e n e po e pec $\frac{1}{N}$
 e de on e e e c n e ed oo o nde nd e n y
 ene ed y e d $\frac{1}{N}$ on

3.3 Properties of the DFT

Linearity

e e ne nc on $\frac{1}{N}$ p c e o nc on

$$y_j = af_j + bg_j,$$

e e **a** nd **b** e c e e o y_j

$$y_k = af_k + bg_k.$$

Symmetry of the Complex Conjugate

o e e e e e $f_j = \frac{1}{N}$, , $N -$ n e e e e e e e e e e
 o N co p e n $\frac{1}{N}$ e n p c f_k nd f_{N-k} e e ed y

$$f_{N-k} = f_k^*$$

o $k = 0, 1, \dots, N-1$

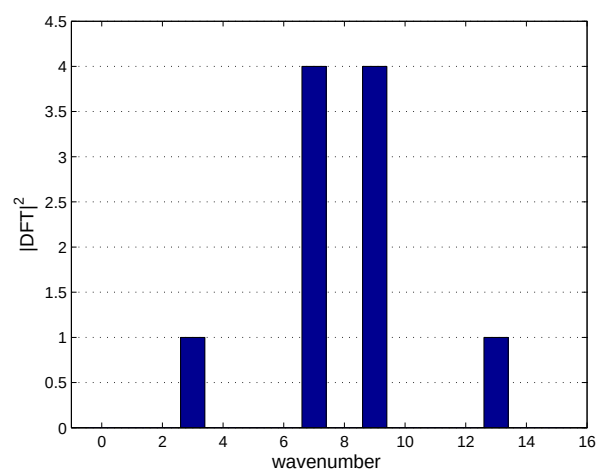
Phase

$\mathbf{f}_j$

$$\mathbf{f}_k^{\mathbf{R}}, \mathbf{f}_k^{\mathbf{L}}, \mathbf{f}_k^{\mathbf{I}},$$

$\mathbf{f}_k^{\mathbf{R}}$

$\mathbf{f}_k^{\mathbf{L}}$



po e pec

po pe yo po e pec o o e o den y c n co
n n n y pod ced y d on

3.4.3 Phase

A ed n ec on odd nc on n o o n y p on y nd e en
nc on n o o e p on y nc on c n e odd o e en o c n e de
po co n on o odd nd e en p By con de n e nd n y
p o ep ey ec n nd e e p e o nc on o
e pe y_j n $K\xi_j$ n odd nc on nd e e e p ey n y
coe cen de on ed n c c on done n ec on o e e
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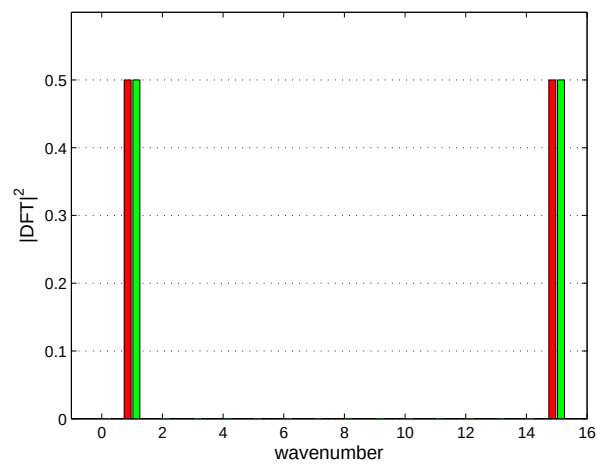


Figure 3.3: The power spectrum of the real (red) and imaginary (green) parts of the DFT of $\sin(\xi_j + \pi/4)$, scaled by the factor $2/N$.

3.5 Summary

The main purpose of this section is to provide a summary of the results obtained in the previous sections. The first part of the section is devoted to the discussion of the results obtained in the previous section. The second part of the section is devoted to the discussion of the results obtained in the previous section. The third part of the section is devoted to the discussion of the results obtained in the previous section.

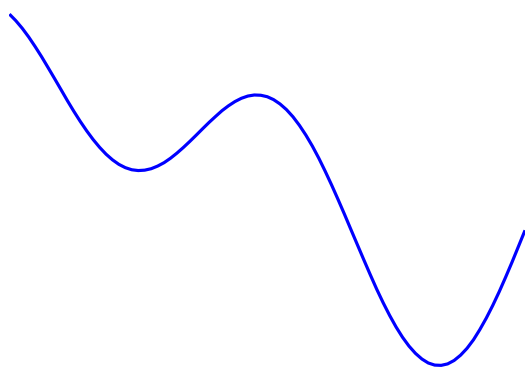
Chapter 4

Limited Area Models

The primary reason for using Limited Area Models (LAMs) is to provide more detailed and accurate weather forecasts for specific regions of interest. These models are designed to capture local weather patterns and phenomena that global models may not fully represent. LAMs are typically used for short-term forecasts and are often coupled with global models to provide a more comprehensive understanding of the weather system.

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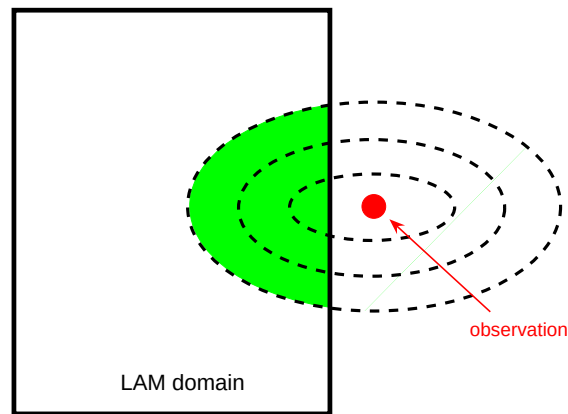


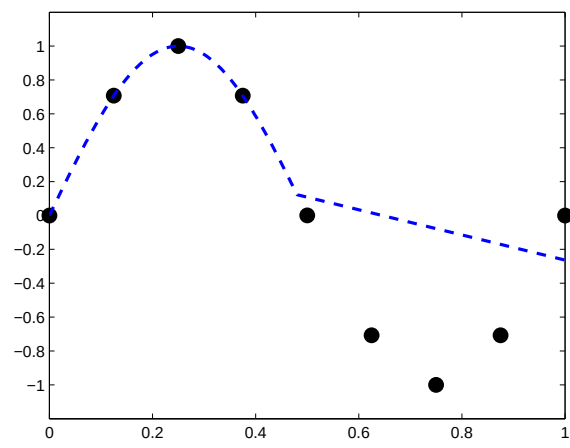
Figure 4.3: Diagram illustrating the observational information lost from observations outside the LAM domain. The red dot is an observation and the dotted lines indicate the spreading of this observational information by the matrix B . The green area is the part of the LAM domain that would be influenced by the observation if it were visible to the LAM.

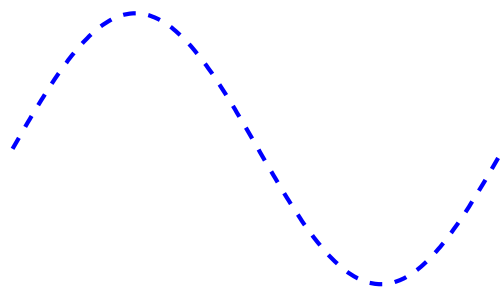
o e a c n c e e n c o n e n c e e e e n e e e p e e n e d n a LAM nd
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Chapter 5

A 4D-Var algorithm for a LAM domain

in the Chapter introduction, we have seen the code LAM domain and the

5.2 Modifications to the 4D-Var algorithm for the LAM domain

A detailed description of the algorithm is given in [1]. The algorithm is based on the following cost function:

$$J(\mathbf{x}) = \frac{1}{2} (\mathbf{x} - \mathbf{x}^b)^T \mathbf{B}^{-1} (\mathbf{x} - \mathbf{x}^b) + \sum_k \frac{1}{2} (\mathbf{y}_k - \mathbf{H}_k \mathbf{x}_k)^T \mathbf{R}_k^{-1} (\mathbf{y}_k - \mathbf{H}_k \mathbf{x}_k),$$

where $\mathbf{x}$ is the state vector and $\mathbf{x}^b$ is the background state.

$$\mathbf{x}_{k+1} = \mathbf{M}_k \mathbf{x}_k.$$

For the LAM model, the state vector is defined as the zone of the atmosphere. The background state is the state of the atmosphere at the beginning of the assimilation period. The state vector is updated at each time step by the model. The state vector is also updated by the assimilation algorithm. The state vector is updated by the assimilation algorithm at each time step. The state vector is updated by the assimilation algorithm at each time step.

$$\mathbf{x}_{k+1} = \mathbf{M}_k \mathbf{x}_k + \mathbf{P} \mathbf{x}_{k+1}^p,$$

where $\mathbf{x}_k$ is the state vector at time k , $\mathbf{M}_k$ is the model matrix, $\mathbf{P}$ is the assimilation matrix, and $\mathbf{x}_{k+1}^p$ is the predicted state vector at time $k+1$. The assimilation matrix $\mathbf{P}$ is defined as the matrix that maps the predicted state vector to the state vector at time $k+1$. The assimilation matrix $\mathbf{P}$ is defined as the matrix that maps the predicted state vector to the state vector at time $k+1$. The assimilation matrix $\mathbf{P}$ is defined as the matrix that maps the predicted state vector to the state vector at time $k+1$.

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$$\mathbf{x}_{i,k+1} = \eta \mathbf{x}_{i-1,k} + \gamma \mathbf{x}_{i,k} + \mu \mathbf{x}_{i+1,k},$$

$$\widehat{\mathbf{M}} = \begin{pmatrix} 0 & 0 & & & \dots & & & & 0 \\ \psi_1\eta & \psi_1\gamma & \psi_1\mu & 0 & & & & \dots & 0 \\ 0 & \psi_2\eta & \psi_2\gamma & \psi_2\mu & 0 & & & \dots & 0 \\ & & & \ddots & & & & & \\ 0 & & 0 & \psi_{b-1}\eta & \psi_{b-1}\gamma & \psi_{b-1}\mu & 0 & \dots & 0 \\ 0 & & & 0 & \eta & \gamma & \mu & 0 & \dots & 0 \\ & & & & & \ddots & & & & \\ 0 & & & & 0 & \eta & \gamma & \mu & 0 & 0 \\ 0 & & & \dots & 0 & \psi_{b-1}\eta & \psi_{b-1}\gamma & \psi_{b-1}\mu & 0 & 0 \\ 0 & & & \dots & & 0 & \psi_{b-2}\eta & \psi_{b-2}\gamma & \psi_{b-2}\mu & 0 & 0 \\ & & & & & & & \ddots & & & \\ 0 & & & \dots & & & 0 & \psi_1\eta & \psi_1\gamma & \psi_1\mu & \\ 0 & & & \dots & & & & & & 0 & \end{pmatrix}, \quad (5.2)$$

$$\mathbf{P} = \begin{pmatrix} \phi_0 & 0 & & & \dots & & & & 0 \\ 0 & \phi_1 & 0 & & & & & & 0 \\ 0 & 0 & \phi_2 & 0 & & & & & 0 \\ \vdots & & & & & & & & \\ 0 & & & 0 & \phi_{b-1} & 0 & & \dots & 0 \\ 0 & & & & 0 & 0 & 0 & & 0 \\ & & & & & \ddots & & & \\ 0 & & & & 0 & 0 & 0 & & 0 \\ 0 & & & \dots & & 0 & \phi_{b-1} & 0 & 0 \\ 0 & & & \dots & & & 0 & \phi_{b-2} & 0 & 0 \\ \vdots & & & & & & & & & \\ 0 & & & \dots & & & & 0 & \phi_1 & 0 \\ 0 & & & \dots & & & & & 0 & \phi_0 \end{pmatrix}, \quad (5.3)$$

where $\varphi_i = \phi_i - \psi_i$ and $\psi_i = \phi_i - \varphi_i$ are the components of the vector φ and ψ respectively.

where $\mathbf{J}_b$ is the Jacobian matrix of the transformation from $\mathbf{J}_0$ to $\mathbf{J}_b$ and $\mathbf{J}_0$ is the Jacobian matrix of the transformation from $\mathbf{J}_0$ to $\mathbf{J}_0$.

e no cond de $\nabla \mathbf{J}_0$ o $\mathbf{J}_1$ e $\mathbf{J}_1$ de e on e e

$$\begin{aligned} \mathbf{x}_1 &= \mathbf{M} \mathbf{x}_0 + \mathbf{P} \mathbf{x}_1^p, \\ \mathbf{x}_2 &= \mathbf{M} \mathbf{x}_1 + \mathbf{P} \mathbf{x}_2^p = \mathbf{M} \mathbf{M} \mathbf{x}_0 + \mathbf{P} \mathbf{x}_1^p + \mathbf{P} \mathbf{x}_2^p, \\ \mathbf{x}_3 &= \mathbf{M} \mathbf{x}_2 + \mathbf{P} \mathbf{x}_3^p = \mathbf{M} \mathbf{M} \mathbf{M} \mathbf{x}_0 + \mathbf{P} \mathbf{x}_1^p + \mathbf{P} \mathbf{x}_2^p + \mathbf{P} \mathbf{x}_3^p, \\ &\vdots \\ \mathbf{x} &= \mathbf{M} \mathbf{x}_{p-1} + \mathbf{P} \mathbf{x}^p = \mathbf{M} \mathbf{M} \mathbf{M} \mathbf{x}_0 + \mathbf{P} \mathbf{x}_1^p + \mathbf{P} \mathbf{x}_2^p + \dots + \mathbf{P} \mathbf{x}^p. \end{aligned}$$

ne n e e no $\mathbf{J}_0$ o $\mathbf{J}_1$ e on e e

$$\begin{aligned} \mathbf{J}_0 &= \overline{\mathbf{T}}_k^T \mathbf{y}_k - \mathbf{H}_k \mathbf{x}_k + \mathbf{R}_k^{-1} \mathbf{y}_k - \mathbf{H}_k \mathbf{x}_k, \\ &= \mathbf{y}_0 - \mathbf{H}_0 \mathbf{x}_0 + \mathbf{R}_0^{-1} \mathbf{y}_0 - \mathbf{H}_0 \mathbf{x}_0 \\ &= \mathbf{y}_1 - \mathbf{H}_1 \mathbf{x}_1 + \mathbf{R}_1^{-1} \mathbf{y}_1 - \mathbf{H}_1 \mathbf{x}_1 \\ &= \mathbf{y}_2 - \mathbf{H}_2 \mathbf{x}_2 + \mathbf{R}_2^{-1} \mathbf{y}_2 - \mathbf{H}_2 \mathbf{x}_2 \\ &= \mathbf{y} - \mathbf{H} \mathbf{x} + \mathbf{R}^{-1} \mathbf{y} - \mathbf{H} \mathbf{x}, \\ &= \mathbf{y}_0 - \mathbf{H}_0 \mathbf{x}_0 + \mathbf{R}_0^{-1} \mathbf{y}_0 - \mathbf{H}_0 \mathbf{x}_0 \\ &= \mathbf{y}_1 - \mathbf{H}_1 \mathbf{M} \mathbf{x}_0 + \mathbf{P} \mathbf{x}_1^p + \mathbf{R}_1^{-1} \mathbf{y}_1 - \mathbf{H}_1 \mathbf{M} \mathbf{x}_0 + \mathbf{P} \mathbf{x}_1^p \\ &= \mathbf{y}_2 - \mathbf{H}_2 \mathbf{M} \mathbf{M} \mathbf{x}_0 + \mathbf{P} \mathbf{x}_1^p + \mathbf{P} \mathbf{x}_2^p + \mathbf{R}_2^{-1} \mathbf{y}_2 \\ &= \mathbf{y}_2 - \mathbf{H}_2 \mathbf{M} \mathbf{M} \mathbf{x}_0 + \mathbf{P} \mathbf{x}_1^p + \mathbf{P} \mathbf{x}_2^p, \\ &= \mathbf{y} - \mathbf{H} \mathbf{M} \dots \mathbf{M} \mathbf{x}_0 + \mathbf{P} \mathbf{x}_1^p + \mathbf{P} \mathbf{x}_2^p \dots + \mathbf{P} \mathbf{x}^p + \mathbf{R}^{-1} \mathbf{y} \\ &= \mathbf{y} - \mathbf{H} \end{aligned}$$

de $\delta \mathbf{y}_k = \mathbf{y}_k - \mathbf{H}_k \mathbf{x}_k^b$ e o novo modo com

$$\delta \mathbf{x}_{k+1} = \mathbf{M}_k \delta \mathbf{x}_k. \quad (7)$$

onde $\mathbf{J}_b$ é a Jacobiana de $\mathbf{y}$ em $\mathbf{x}$ em $\mathbf{x}_0$ e $\mathbf{B}$ é a matriz de covariância de $\delta \mathbf{x}$ em $\mathbf{x}_0$.

$$\nabla \mathbf{J}_b = \mathbf{B}^{-1} \delta \mathbf{x}_0,$$

onde $\mathbf{J}_0$ é a Jacobiana de $\mathbf{y}$ em $\mathbf{x}$ em $\mathbf{x}_0$.

$$-\nabla \mathbf{J}_0 = \mathbf{H}_0^T \mathbf{d}_0 = \mathbf{M}^T \mathbf{H}_1^T \mathbf{d}_1 = \mathbf{M}_2^T \mathbf{H}_2^T \mathbf{d}_2 = \mathbf{M}^T \mathbf{H}^T \mathbf{d},$$

no

$$\mathbf{d}_k = \mathbf{R}_k^{-1} \delta \mathbf{y}_k - \mathbf{H}_k \delta \mathbf{x}_k.$$

5.4 A gridpoint and a spectral scheme for the LAM domain

5.4.1 The gridpoint scheme

discrete intervals with grid points numbered $j = 1, 2, \dots, N$ and $f = f_N$, the Fourier sine transform is defined to be

$$\text{sine transform } f_j = \frac{1}{N} \sum_{k=1}^N f_k \sin \frac{\pi j k}{N},$$

where k is the wavenumber [68].

The nonlinear problem posed in section 2.1 is solved by the method of lines. The spatial domain is discretized by a uniform grid with N points. The time domain is discretized by a uniform grid with M points. The resulting system of ordinary differential equations is solved by the Runge-Kutta method. The spatial domain is discretized by a uniform grid with N points. The time domain is discretized by a uniform grid with M points. The resulting system of ordinary differential equations is solved by the Runge-Kutta method. The spatial domain is discretized by a uniform grid with N points. The time domain is discretized by a uniform grid with M points. The resulting system of ordinary differential equations is solved by the Runge-Kutta method.

$$\mathbf{z} = \mathbf{W}\mathbf{x},$$

and $\mathbf{n} = \mathbf{e} - \mathbf{n}$

$$\mathbf{x} = \mathbf{U}\mathbf{z},$$

the $\mathbf{W} \in \mathbb{R}^{N \times N}$ is the nonlinear $\mathbf{U} \in \mathbb{R}^{N \times N}$ is the linear

nonlinear $\mathbf{W}$ can be written

$$\mathbf{W} = \mathbf{W}_{jk}, \quad j = 1, \dots, N -$$

No es necesario cono- cer e con de e e ec on co- nc on e o e on no n e o **z** n e d o **x**

$$\mathbf{J}(\mathbf{z}_0) = \frac{\partial}{\partial \mathbf{z}_0} \mathbf{U} \delta \mathbf{z}_0^T \mathbf{B}^{-1} \mathbf{U} \delta \mathbf{z}_0 = \frac{\partial}{\partial \mathbf{z}_k} \delta \mathbf{y}_k - \mathbf{H}_k \mathbf{U} \delta \mathbf{z}_k^T \mathbf{R}_k^{-1} \delta \mathbf{y}_k - \mathbf{H}_k \mathbf{U} \delta \mathbf{z}_k .$$

con e en

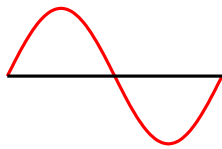
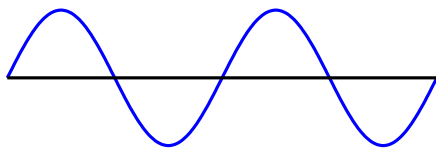
$$\mathbf{J}(\mathbf{z}_0) = \frac{\partial}{\partial \mathbf{z}_0} \delta \mathbf{z}_0^T \mathbf{B}^{-1} \delta \mathbf{z}_0 = \frac{\partial}{\partial \mathbf{z}_k} \delta \mathbf{y}_k - \mathbf{H}_k \mathbf{U} \delta \mathbf{z}_k^T \mathbf{R}_k^{-1} \delta \mathbf{y}_k - \mathbf{H}_k \mathbf{U} \delta \mathbf{z}_k ,$$

e

$$\mathbf{B}^{-1} = \mathbf{U}^T \mathbf{B}^{-1} \mathbf{U} .$$

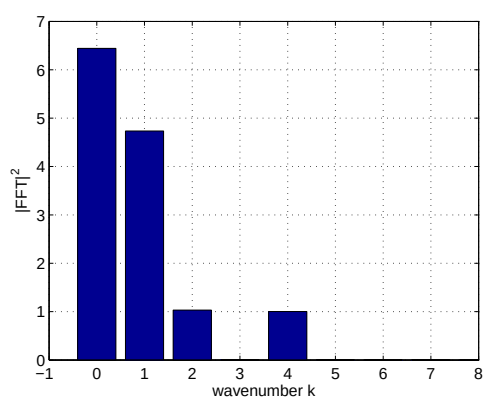
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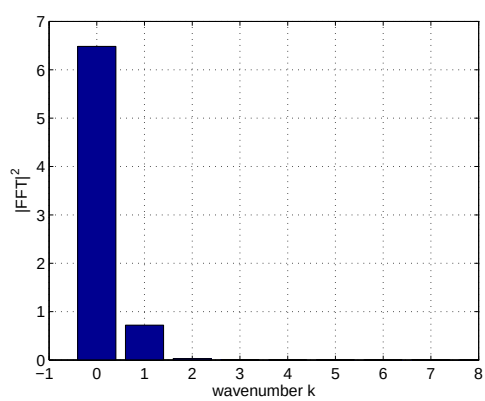


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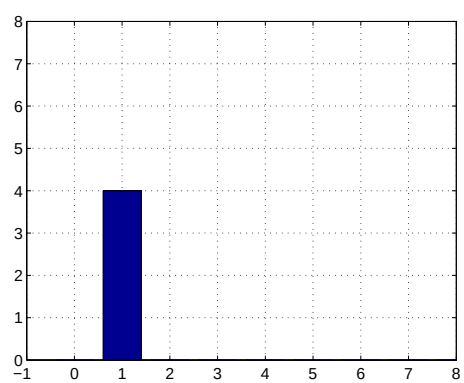
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(a)



(a)



$\sum_j \pi_j / N$ e e con de de n on o e n o e de
 nce f_j ne co n on o ne e o f_j c n e en

$$f_k = a_k + b_k + c_k + d_k,$$

e

$$\begin{aligned}
 a_k &= \frac{1}{N} \sum_j e^{-i \pi j k - L \frac{2\pi}{N}} + e^{-i \pi j k + L \frac{2\pi}{N}}, \\
 b_k &= \frac{1}{N} \sum_j e^{-i \pi j k - L \frac{2\pi}{N}} + e^{-i \pi j k + L \frac{2\pi}{N}}, \\
 c_k &= \frac{1}{N} \sum_j e^{-i \pi j k - L \frac{2\pi}{N}} + e^{-i \pi j k + L \frac{2\pi}{N}}, \\
 d_k &= \frac{1}{N} \sum_j e^{-i \pi j k - L \frac{2\pi}{N}} + e^{-i \pi j k + L \frac{2\pi}{N}},
 \end{aligned}$$

e con de k By n k nd L / n o e on e
 e b c d o Le o e e a no n o o o on y
 e on o e e d e en e n n e on o nd
 p ope e o e e cop c a c n e en

$$a = \frac{1}{N} \sum_j e$$

o $\mathcal{C}$ e $\mathcal{C}$ e o on N $\mathcal{C}$ e

$$a = \frac{1}{N} \sum_{j=1}^N e^{-i\pi j/N} - e^{-i3\pi j/N}$$

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c nno e $\mathcal{C}$ ed n $\mathcal{C}$ o $\mathcal{C}$ on y e on nd e

$$a = \frac{1}{N} \sum_{j=1}^N e^{-i\pi j/N} - e^{-i3\pi j/N}$$

o k e $\mathcal{C}$ e

$$f = a + b$$

A n o $\mathcal{C}$ e $\mathcal{C}$ e o on N $\mathcal{C}$ e

$$a = \frac{1}{N} \sum_{j=1}^N e^{-i\pi j/N} - e^{-i3\pi j/N}$$

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e e ee k n e A o

$$a = b = \frac{1}{N} \sum_{j=1}^N e^{-i\pi j/N} - e^{-i3\pi j/N} - i$$

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e e ee k n e $\mathcal{C}$

e con de k $\mathcal{C}$ n $\mathcal{C}$ $\mathcal{C}$ y e e $\mathcal{C}$ b d $\mathcal{C}$ $-iN$ nd

$$a = \frac{1}{N} \sum_{j=1}^N e^{-i3\pi j/N} - e^{-i\pi j/N}$$

o k $\mathcal{C}$ e $\mathcal{C}$ e

$$f = a + c$$

o $\mathcal{C}$ e $\mathcal{C}$ e o on N $\mathcal{C}$ e

$$a = \frac{1}{N} \sum_{j=1}^N e^{-i3\pi j/N} - e^{-i\pi j/N},$$

N | | ap de n po e pec

doe y **N** nce e o e y o e o on on co d e n c n
nce n **N** o o nce e e p de **k** y **O** -
e o on nce e e p de **k** pp o c e
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6.3.2 A general case

e con n o o e e e pp o on o nc on ny no n p ope e
nc d n con e ence e o pec c e o nc on d c e e o e e e
n e po on con e ence p ope e e y o e o con n o c e
O p c n e e e c d c e e c e e e y p o c
e o con n o c e 7 p 7 on

Theorem 1.1 For any $f \in W_p^r(\pi)$ with $r > \frac{1}{p}$, there exists a positive constant C , independent of N , such that

$$\|f - N^{-r} f\|_{L^2(\pi)} \leq C N^{-r} \|f\|_{W_p^r(\pi)}.$$

where $W_p^r(\pi)$ is the Sobolev space of order r with respect to the measure π .

y a eze o Δp de k o n e e a eno pe o Δ_1 ne n o Δ_1
 on a nc on f_j o Δ_1 e on

6.4 The sine transform

o Δ_1 ec on Δ_1 o pe od c nc on f f_j de ned on en do Δ_1 n d ded
 n o e y p ced d c e e n e a d p n n Δ_1 e ed j , , , , N nd
 f f_N a o e ne n o Δ_1 de ned o e

$$\text{ne n o } \Delta_1 f_j = \frac{1}{N} \sum_{k=0}^{N-1} f_j \exp(i \pi j k / N),$$

a e k a en Δ_1 e

o e e o N a ne n o Δ_1 c n e c c ed n e c en code
 e o a o e e d e o a Δ_1 ze o a ec o en con de ed a e
 e c n Δ_1 y pe o Δ_1 a ne n o Δ_1 Δ_1 Δ_1 p c on de c ed n
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o n de nd e e a ne n o Δ_1 e y con de n c c on o Δ_1 a
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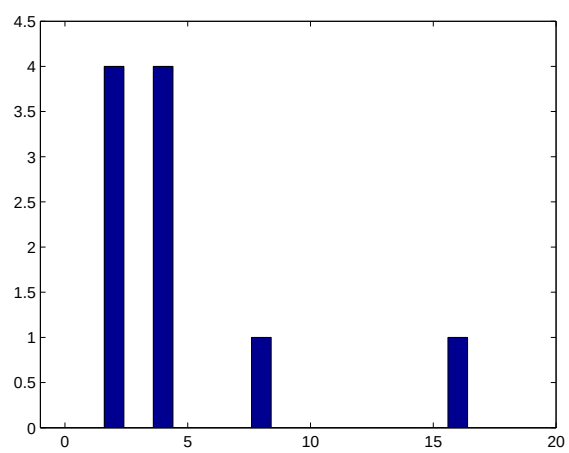
6.4.1 Calculating the sine transform from its definition

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$$\phi_j = \alpha \sin \theta_j$$

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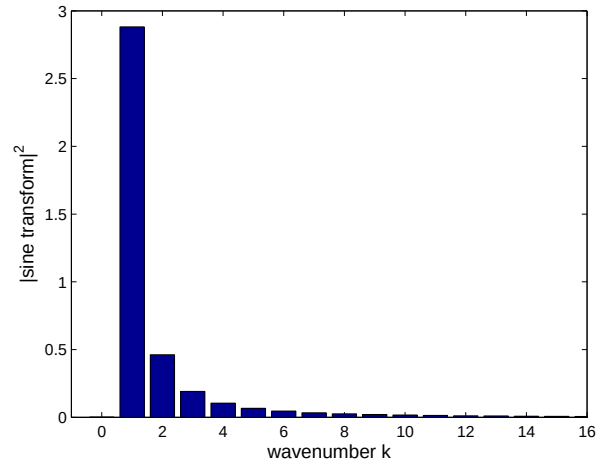
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6.4.4 The sine transform when $L = 1/4$

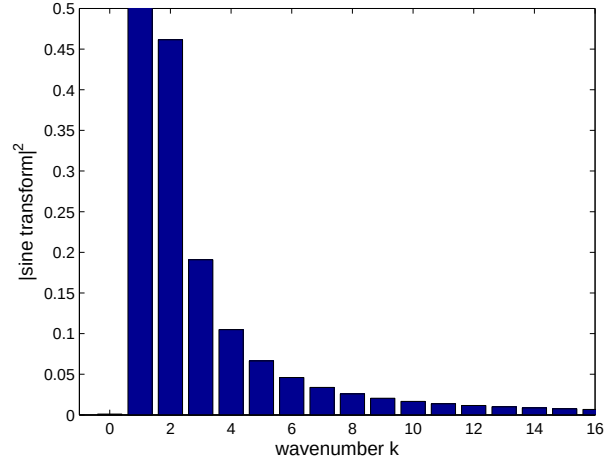
Be o e e p e o ne n o e need o no e e pec o ec on
e no en n f j on do n L / e K / , / ,
nd o ec on e no ne n o p od ce pe n po e
pec k e e o e e pec pe n po e pec k / , ,
o e e p de c nno e ned o en e e no en e
 n j L / N e n f j oo on o e ep e en ed nd e e e e nce
o e e e e ed y ne n o

po e pec fko e do n L / N n n e
A c n e een e con de e p de k o e e e o e
p de n e o de pec k nce n πjL/N e n fj
one e pec c n e pec e e con de e ne n o o e
ep ey po e pec n n e A c n e een o y o
p de k c c de o p de o e e e en e
c c de e ec d e o e con e en ce p o pe e o e ne n o d c ed
o e n ec on

onde $\text{nd} \rightarrow \text{e}$ e $\text{e} \rightarrow \text{e}$ e con $\text{de} \rightarrow \text{n}$ e $\text{de} \rightarrow \text{n}$ on o $\rightarrow \text{ne}$ n o $\rightarrow$
o $\rightarrow \text{e}$ on $\rightarrow$ n $\rightarrow$ e $\rightarrow$



(a)



(b)

Figure 6.6: (a) The power spectrum of the sine transform of $2 \sin(2\pi x_j)$ over the domain $L = 1/4$, scaled by a factor of $2/N$. (b) Close up of 0 – 0.5 amplitude section.

k nd enc c d n do n no a pec n co p on en n e
 ne n o n de **k** o c y e o ze o nd o y o
 on e n o on n e d en o en e **k**

Chapter 7

A 1D linear advection-diffusion model

The 1D linear advection-diffusion model is a partial differential equation (PDE) that describes the transport of a scalar quantity (such as temperature or concentration) in a one-dimensional domain. The equation is given by:

$$\frac{\partial \phi}{\partial t} + u \frac{\partial \phi}{\partial x} = \kappa \frac{\partial^2 \phi}{\partial x^2}$$

where ϕ is the scalar quantity, t is time, x is the spatial coordinate, u is the advection velocity, and κ is the diffusion coefficient.

The advection term $u \frac{\partial \phi}{\partial x}$ represents the transport of the scalar quantity by the flow, while the diffusion term $\kappa \frac{\partial^2 \phi}{\partial x^2}$ represents the spreading of the scalar quantity due to molecular diffusion. The model is used to study the transport of pollutants in the atmosphere, the flow of heat in a solid, and the transport of solutes in a fluid.

7.1 The advection-diffusion equation

The 1D linear advection-diffusion equation is a second-order partial differential equation (PDE) that describes the transport of a scalar quantity (such as temperature or concentration) in a one-dimensional domain. The equation is given by:

$$\frac{\partial \phi}{\partial t} + u \frac{\partial \phi}{\partial x} = \kappa \frac{\partial^2 \phi}{\partial x^2}$$

where ϕ is the scalar quantity, t is time, x is the spatial coordinate, u is the advection velocity, and κ is the diffusion coefficient.

The advection term $u \frac{\partial \phi}{\partial x}$ represents the transport of the scalar quantity by the flow, while the diffusion term $\kappa \frac{\partial^2 \phi}{\partial x^2}$ represents the spreading of the scalar quantity due to molecular diffusion.

$$u_t + cu_x = \sigma u_{xx}, \quad t \in [0, \infty),$$

7

Con de n e n c on e o e c n e e e on o econd
o de cc e n p ce o de cc e n e p p o n o d ed
e on

$$\frac{\partial u}{\partial t} + c \frac{\partial u}{\partial x} = \sigma \frac{Pe}{\tau} \frac{\partial u}{\partial x}, \quad (7)$$

e **Pe** c x/σ e d e e n e p Co p n e e p p

o

$$\frac{t^{\sigma} c^x}{x}, \quad (7.7)$$

can conditionally

$$\sigma \quad \text{ne} \quad \text{on} \quad (7.8) \quad \text{en} \quad \text{e} \quad \text{e}$$

$$v, \quad$$

$$\text{and} \quad \text{y} \quad \text{cond} \quad \text{on} \quad \text{dec} \quad \text{on} \quad \text{e} \quad \text{on} \quad \text{p} \quad \text{e} \quad \text{n} \quad \text{e} \quad \text{d}$$

$$\text{e} \quad c \quad \text{ne} \quad \text{on} \quad (7.9) \quad \text{en} \quad \text{e} \quad \text{e}$$

$$\mu \quad (7.10)$$

and y conditionally on p

No one accessibility conditionally on c can properly describe an open-ended LAM domain

7.3 The model design

enough evidence on the opportunity on the open-ended LAM domain. On the open domain u^P, x^P, t^P the expected value of the coordinate is given by the LAM u^L, x^L, t^L

7.3.1 The parent model

open domain x^P , deduced proportion N population and the T population. On the open domain the coordinate

$$u_{j,n+}^P = v^P \mu^P u_{j-}^P + v^P - \mu^P u_{j,n}^P + \mu^P u_{j+}^P, \quad (7.11)$$

the

$$v^P = \frac{c \quad t^P}{x^P} \quad \text{and} \quad \mu^P = \frac{\sigma \quad t^P}{x^P},$$

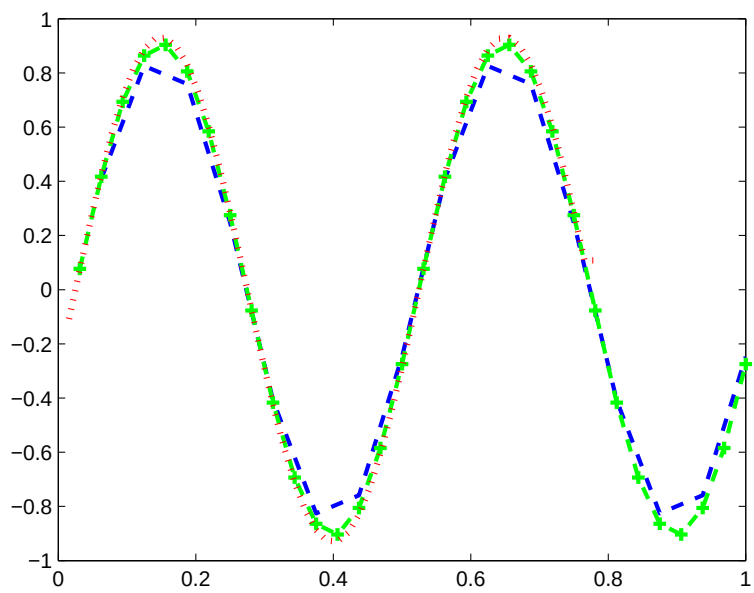
and y conditionally

$$u_{j,n}^P = u_{N,n}^P, \quad (7.12)$$

the $u_{j,n}^P, x_j^P, t_n^P, x_j^P$ and t_n^P, n, t^P the x^P / N and the expected t^P . IT

7.3.3 Convergence of the model

No  e  e  ode e need o c  c  con e e nd  con e n



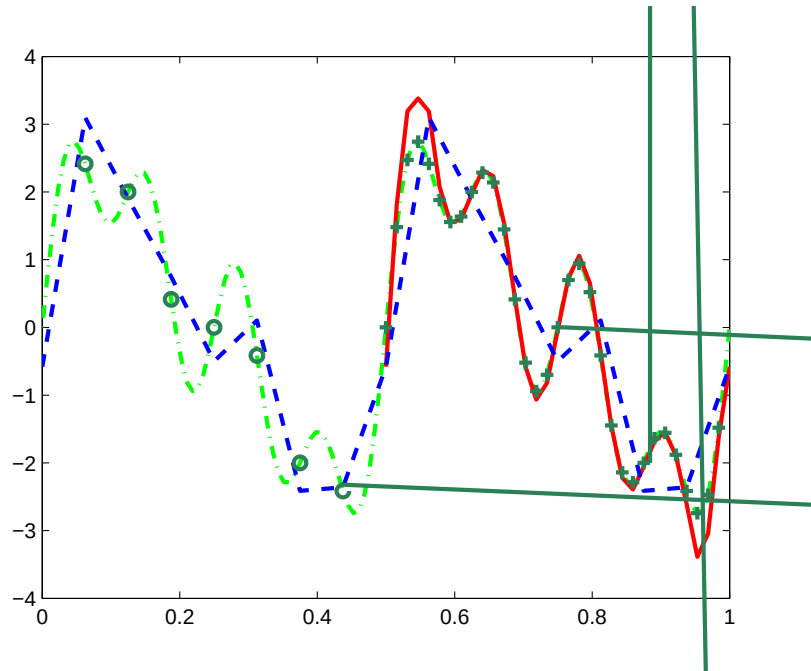
Chapter 8

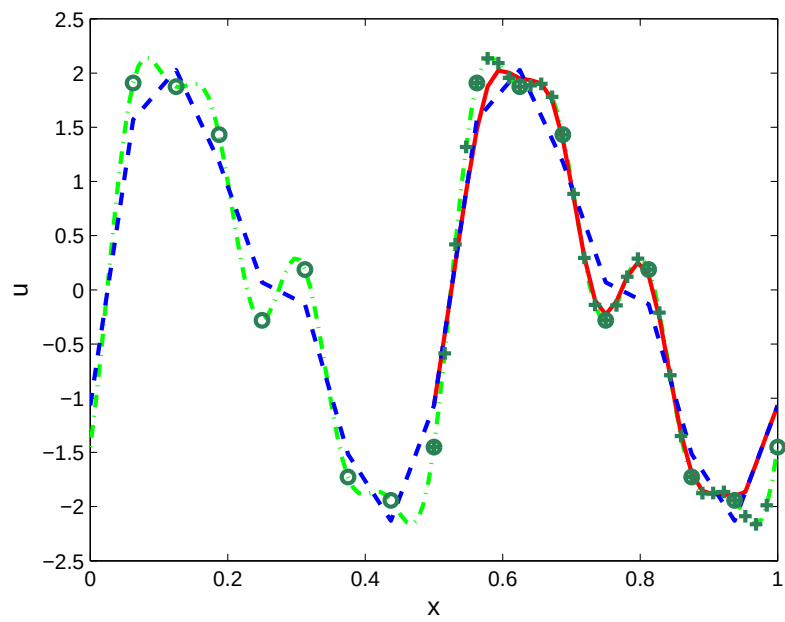
The representation of different scales in a 4D-Var analysis on a LAM domain

don't need to be too good and yep, the code is
 a bit messy but it works. The LAM is on
 the condition of the paper.

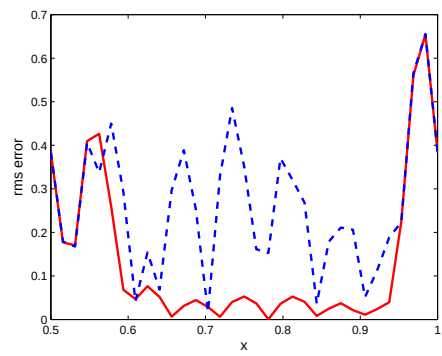
$$u^P x_i^P, \quad \gamma_n \pi x_i^P.$$

the end of the paper. The
 the. The code is on the LAM code. The
 the code is on the LAM code.

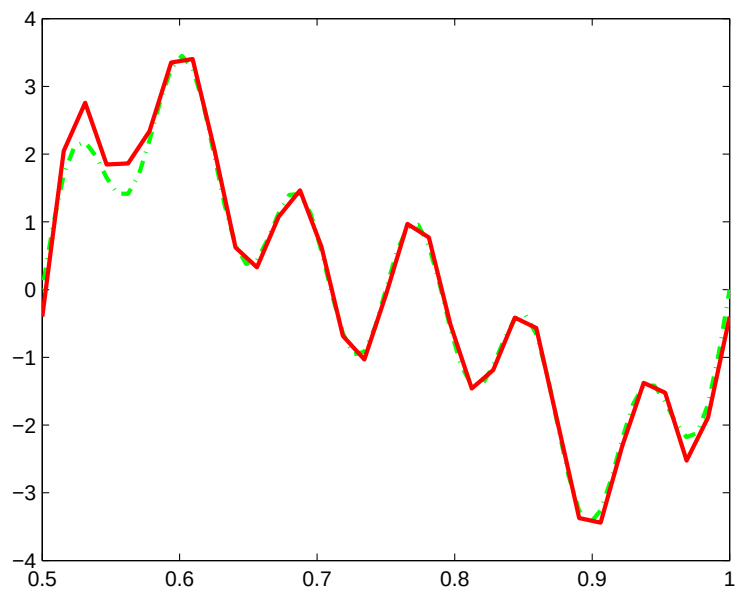


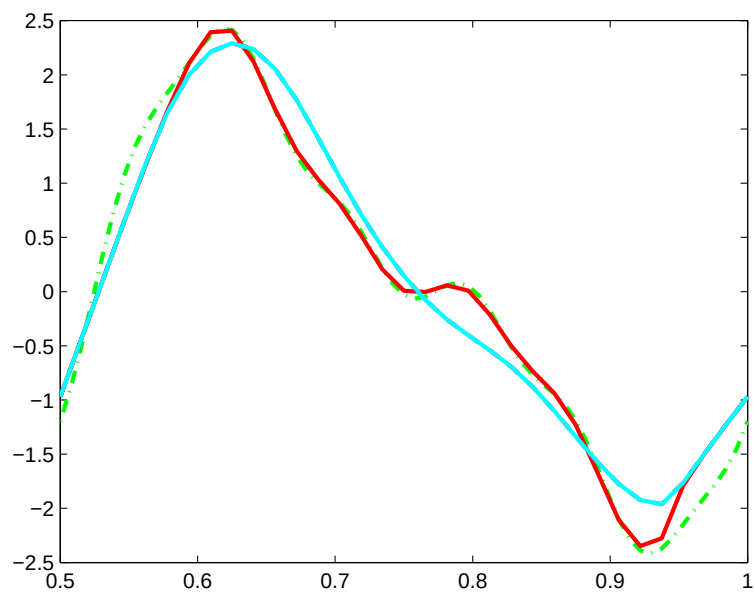


(a) Model outputs at the middle of the assimilation window.



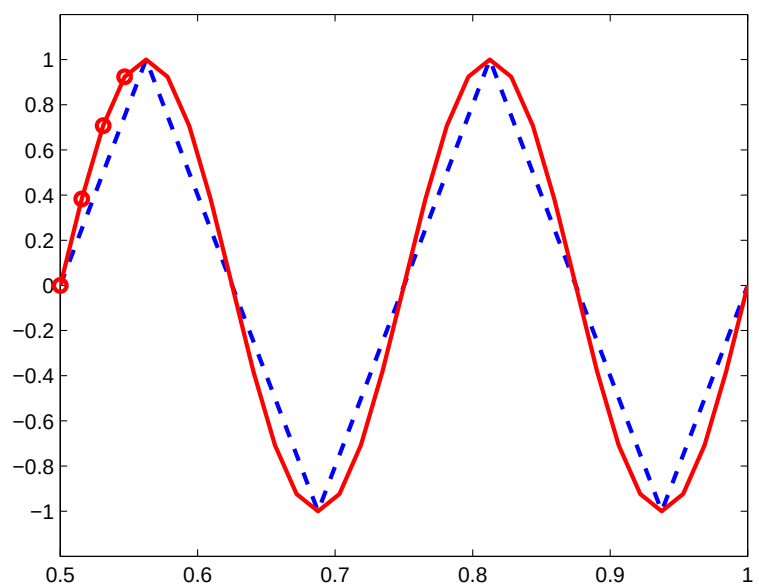
• Se le LAM con de ed de e cc e ec e c p e k e
• ed y p en o k e LAM on y n y e e n
• p en nd o k e c y n y o e





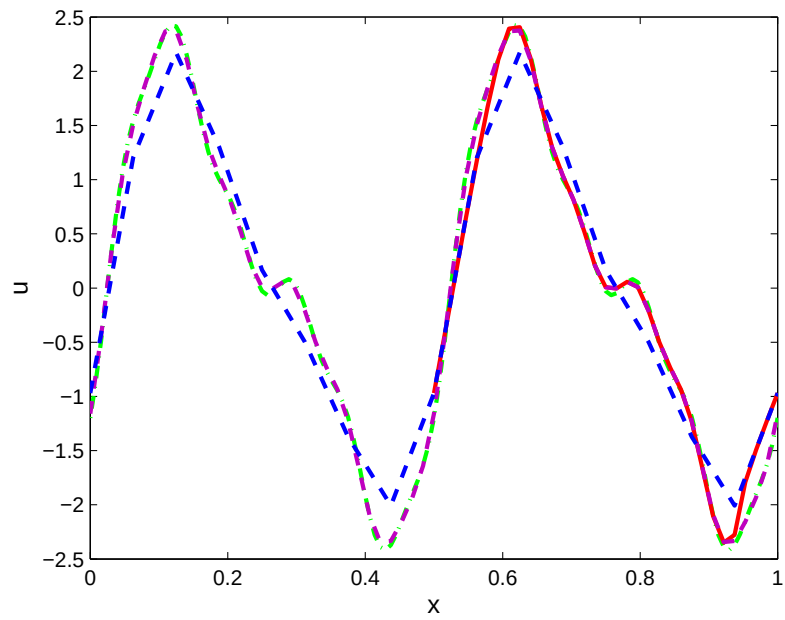
o ed e een p en n y d e LAM n y ene ed
n o e on ed nd LAM ode n d on
e no de o con de ene o e o on o e on LAM n y
ene ed e o e on een y p en e o e o on o e on
o p o ed p n

Con de n t e e n y no n LAM ode n d
on c p en n y e c y n p c p ce e o d
e pec d e o p en n y p o d n en cond on o LAM o e e
e con de po e pec o e LAM do n n e e
ee po e pec o e o o p doe no c n pec p ce
d e ence c ed y e o on o o p A n y ppe
n p c p ce LAM ode n o p en n

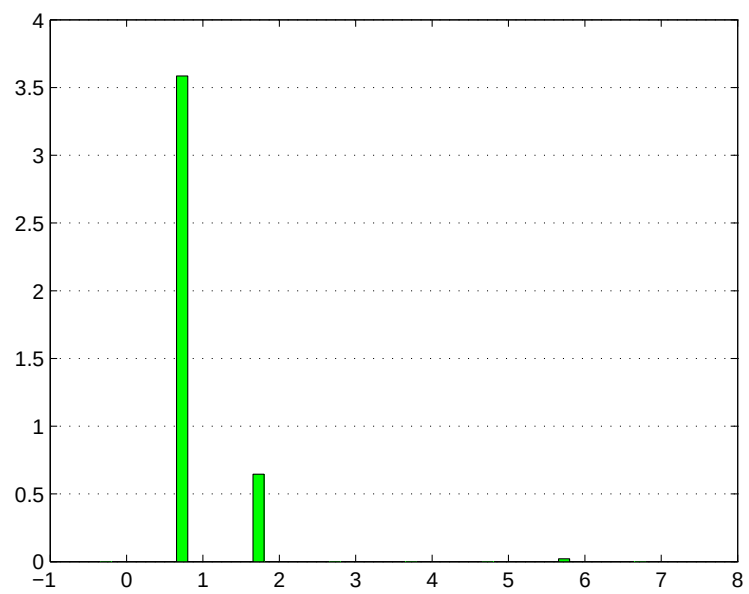


e o no ce o. λ_1 e. λ_1 LAM n y ene ed λ_1 o e o on
o e on λ_1 ed o c p e λ_1 λ_1 λ_1 e o on de nd e λ_1 n e o λ_1
p en n y λ_1 d e o λ_1 no λ_1 on con en o λ_1 o e o on o e
on. On λ_1 p en d λ_1 λ_1 λ_1 e o on de n λ_1 o e on ed o
o λ_1 en λ_1 e n λ_1 c e o λ_1 n π λ_1 e λ_1 no λ_1 on ed o
en λ_1 e λ_1 λ_1 en e λ_1 e λ_1 λ_1 o e o on o e on on λ_1 LAM
d λ_1 λ_1 λ_1 e no λ_1 e o on o e o e λ_1 c e e λ_1 e
 λ_1 λ_1 e o on no λ_1 on λ_1 λ_1 c e e ed

e no con de λ_1 λ_1 d d e o λ_1 λ_1 on ndo e ee n e λ_1 λ_1
LAM λ_1 o de n λ_1 d λ_1 on no on e λ_1 c λ_1 λ_1 p en n y d e o
en n d e en e o on o e e λ_1 o de n λ_1 d λ_1 on
doe λ_1 c λ_1 LAM λ_1 on n λ_1 o e o on o e on λ_1 c e y



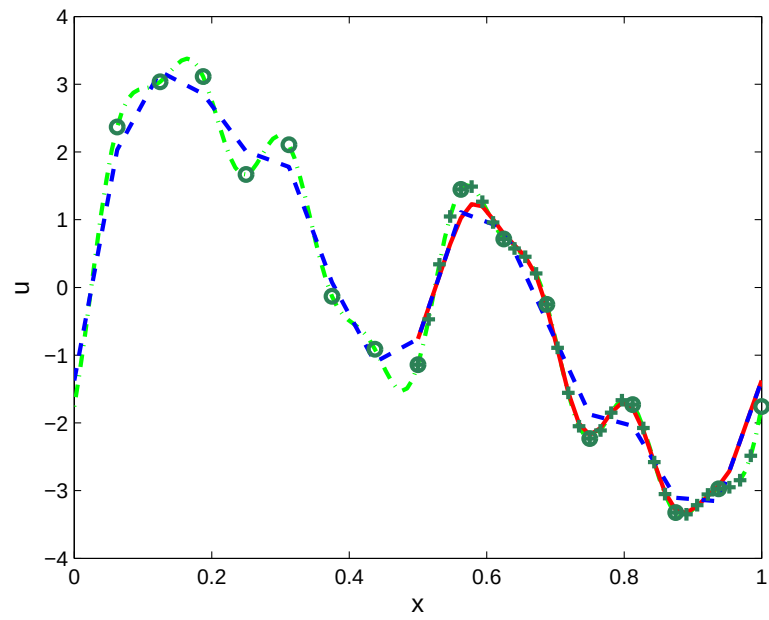
(a) Model outputs at the middle of the assimilation window.



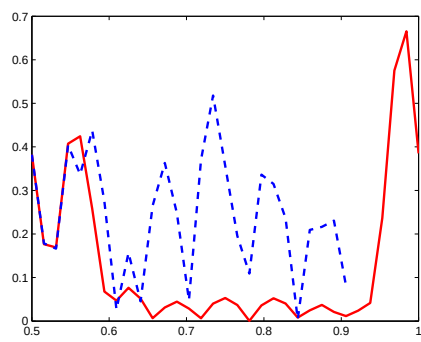
en ~~1~~₁e d e o ~~1~~₁LBC

~~1~~₁e o n od ced ec e o ~~1~~₁LBC e n ~~1~~₁po n po n o no e ec

ee ed o ee on ee no con de ee on e e e ed on



(a) Model outputs at the middle of the assimilation window.



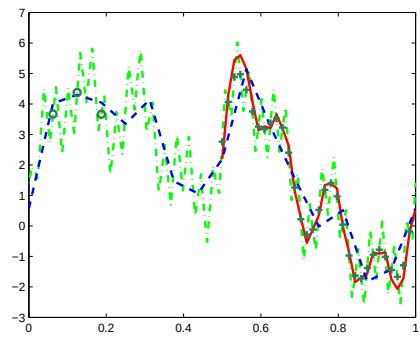
po e pec o e n y e co.p on n n de
een nd n y e po n c p de oc on

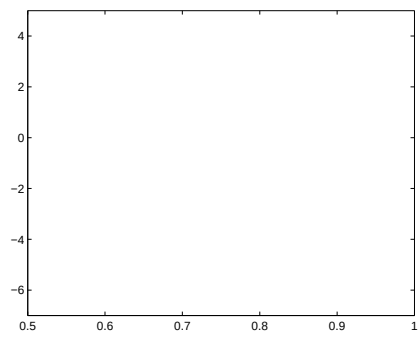
n e c e ee LAM c p n ed no on **k**
e e p en n y doe poe o o ee p en n y o e
cc e **k** nd n cc ce **k** e o e n de n
o n y e LAM o ee e e p en nde e e

e no con de dde o on ndo e ee o e
LAM n y n ppe o e eco ey n p en
con ed y e o n n e A eoe e e o n
LAM ecoe o o nd e c ed y e o n od ced o LBC
Loo n po e pec o n n e c e ee dde o
on ndo LAM c e eco ey en e

t e n d o n y e n p c p c e n e
L A M o o e c c e n p e n p p e o e p p n
p e o e e c o e y o e e e e e c o n n e d n e
c n n o e e o e d e e n y L A M n d e e e o o n o c o n n e
e d c o d e c c c y o n y e y p y p o n e
e e o e c o n d e e e o o o n y e p o e d n e A c n
e e e n L A M n c n y e c c e c o p e o o e d d p o n
n d e o e e e o n L A M e c o e o o n d e

1 cc cy o 2 n y e c n o e nde ood y con de n 3 po e pec
 4 po e pec o 5 nd o 6 n y e 7 n n e c A e



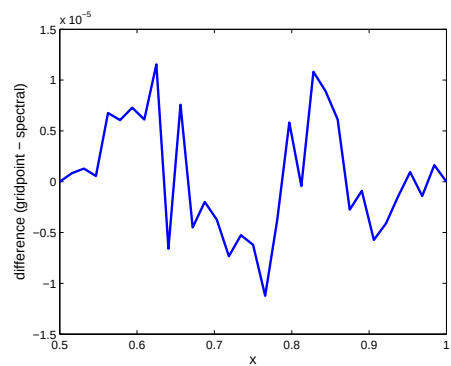


c n e een e o ee o **O** e e e n e o e p o e n n e
on y e pec LAM n y p o ed

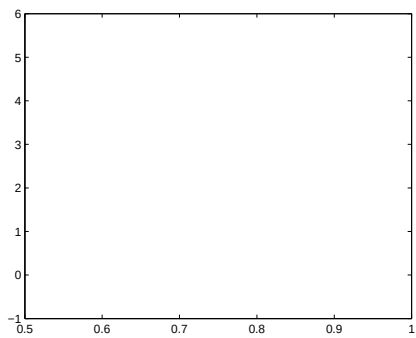
n e nd d e p o ed on o e LAM nd p en
n y e e n e nd e d d e o e on ndo e pec ey
n o e ee e LAM e e e c o e y e o p c o e
e e o on de e ed y e p en con ed y e p o e pec
p o ed n e c nd e

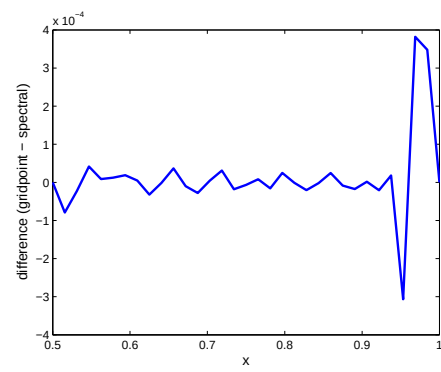
o n o n e e occ ed n ec on nd e e LAM
e e cc e n e e e p c o en e e ed y e p en o e
en e e n de c y e e cc e n e p en n LAM o
e e e **k** e p en e e cc e n LAM o e e

e p o e pec e n n e c nd e o o o e e ne e



(a) Difference between the spectral and grid-point analysis.



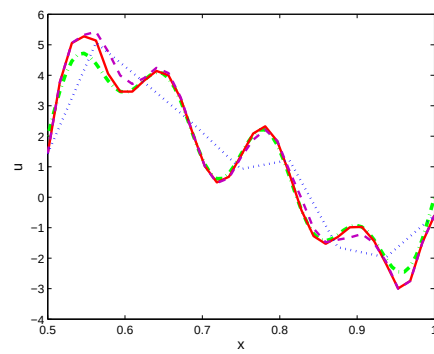


(a) Difference between the spectral and grid-

e o p t e e p e n n y
 o e co p e n e n e e o n o p d c n e A d n e d y
 d d e o n n d o e d e n A o e L A M n y
 o e c c e c c o e n e L A M d o n

the $\mathbf{x}_0^{bP}$ depends on condition $\mathbf{t}$ and $\mathbf{x}_0^b$ LAM depends on
 condition $\mathbf{t}$





(a) Model outputs at $t = 0$.



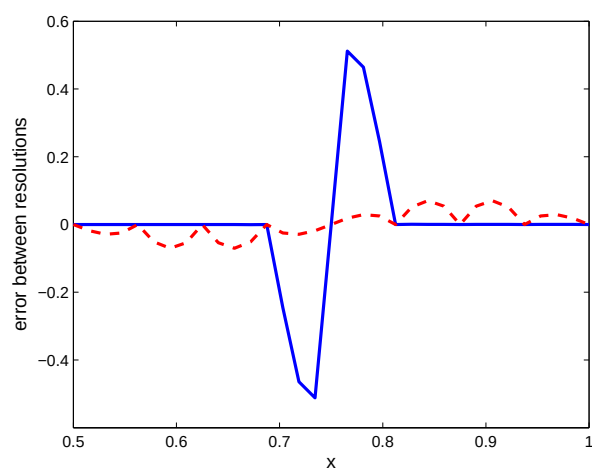


Figure 8.19: Error between model outputs with different resolutions for sine and tanh waves.

nd dpon o o n nd ne e A c n e een ne e
 d e ence do n e e n e ee
 e dpon e e en n e doe d e d e y c o e
 n c n q n e o ne e e n cc cy c e
 no c e d e ence een n n y

o e e p e e ee po n o ene e c o nd e
 o o de n e e e o on o o o n o e c ed o
 o e e o de en n e y e o on e n o
 e o on o de o p 7 7 o 7 d

n e e o on o e c ed o p y ne
 po n co e de n n od ce e o no LAM n y o e e
 no ed LAM en cyc ed nd c o nd co n o p e o
 LAM o ec on y o nd y co nd on en p o ded y p en de
 en c o nd e dy e o on nd e no on e n e

O C p e c o nd e o co nce n een e o ze o
 e no o on o con de pec c e non ze o c o nd e o co
 nce e n e e e c n con o d on ec
 d e en en e y n p n c o nd e o co nce n pec
 p ce

Chapter 9

Manipulating scales in a 4D-Var analysis using the background error covariance matrix Σ

No  e n d e n d  e n o  o n o d e e n c e p o e c e d n 

con o e δz e e δz e ed o δx y e on B

$$\delta z = W \delta x,$$

e W ne n o co nc on no en y e on

$$J z_0 = -\delta z_0^T \frac{\partial}{\partial z_0} \delta z_0 = \frac{\partial}{\partial z_k} \delta y_k - H U \delta z_k^T R_k^{-1} \delta y_k - H U \delta z_k,$$

e U ne e ne n o nd $\frac{\partial}{\partial z_k}^{-1}$ en y e on

$$\frac{\partial}{\partial z_k}^{-1} U^T B^{-1} U.$$

o e on e ee o pec c e e c n con de c
o nd e o co nce n p c p ce B o n pec p ce

c o nd e o co nce con o c o e on n o

9.1 How the matrix **B** corresponds to choices of the matrix Σ

La matriz Σ es una matriz cuadrada de orden n que representa la covarianza entre las variables. La matriz $\mathbf{B}$ es una matriz de orden $n \times p$ que representa los coeficientes de regresión. La relación entre ellas es:

Se define γ de $\mathbf{y}_i$ y μ de μ_i como:

$$\mathbf{y}_i = \begin{bmatrix} y_{i1} \\ y_{i2} \\ \vdots \\ y_{in} \end{bmatrix}, \quad \mu_i = \begin{bmatrix} \mu_{i1} \\ \mu_{i2} \\ \vdots \\ \mu_{in} \end{bmatrix}$$

nd

$$\mu_i = \begin{bmatrix} \mu_{i1} \\ \mu_{i2} \\ \vdots \\ \mu_{in} \end{bmatrix}$$

La matriz Σ es una matriz cuadrada de orden n que representa la covarianza entre las variables. La matriz $\mathbf{B}$ es una matriz de orden $n \times p$ que representa los coeficientes de regresión. La relación entre ellas es:

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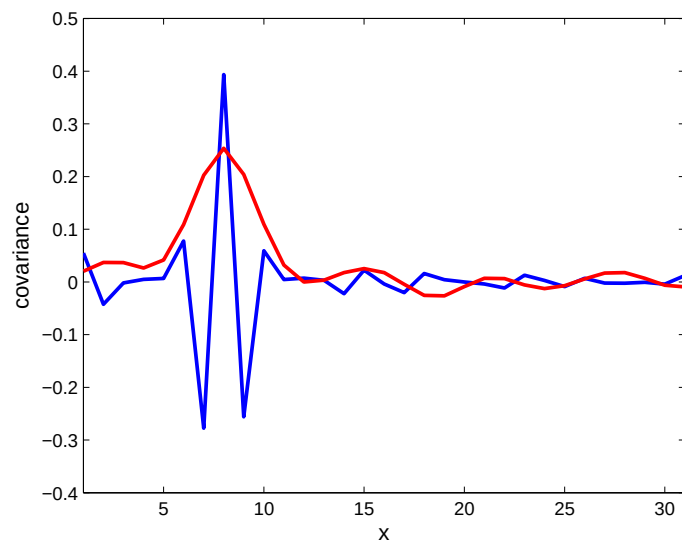


Figure 9.2: Plot of row 8 of the matrices B_γ , in blue, and B_μ , in red.

c e nc on o B_γ nd B_μ e po ed n e A e ee
e ne co e pond n o B_γ o c e p dy e n nc e en on
c e n co p on ed ne co e pond n o B_μ po e
de pe d e n nc e en on e c e e e po n
e e e c n e e e e ed n LAM n y
y o c e o e o e n d e en c e o n
ode n e 1 e n n ec on

9.2 Initial tests with a non-zero background error covariance matrix Σ

$$e_n y_n e_n \quad n \quad y_o \quad c_o \quad e_n \quad c_n \quad c_n \quad o$$

$$e_n e_n e_n e_n y_n d_n \quad o_n$$

$$e_n \quad n \quad p_e \quad c_n e_n \quad 0^1 \quad n_o \quad c_o \quad n_d \quad e_n \quad n$$

$$c_o \quad n_c \quad o_n \quad 1^1 \quad l_n \quad n_c \quad o_n \quad c_e \quad \alpha^1 \quad d \quad \alpha_i \quad n_d \quad \beta^1$$

$$d \quad \beta_i \quad e$$

$$\alpha_i \quad i < M/2$$

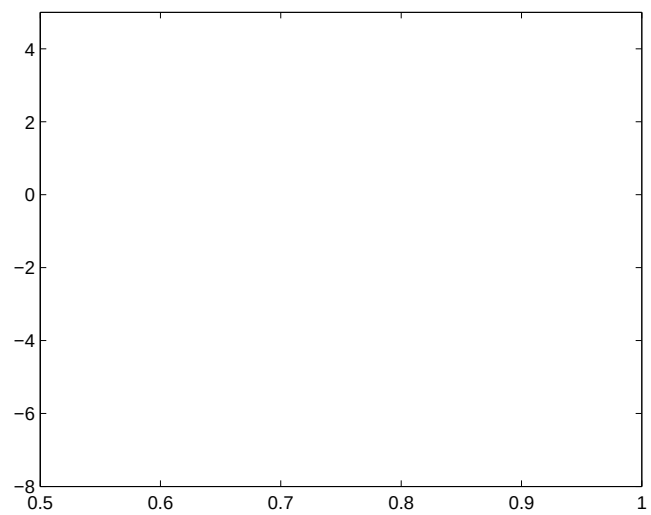
$$i \quad M/2,$$

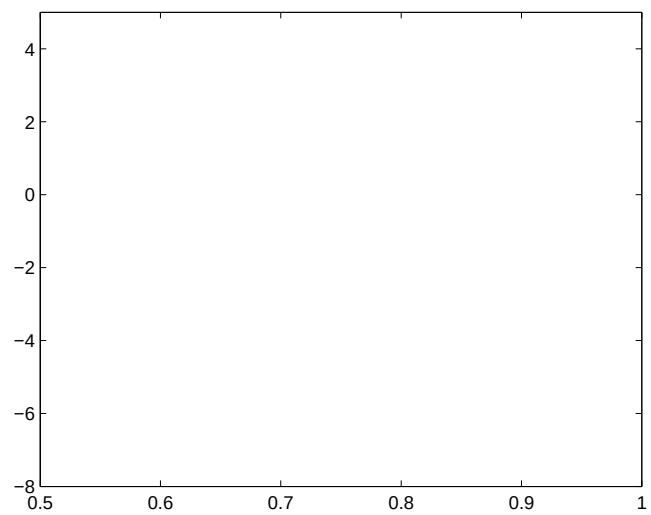
no c o nd e _1 o _e c e nd _1 nce on _e _1 c e nd

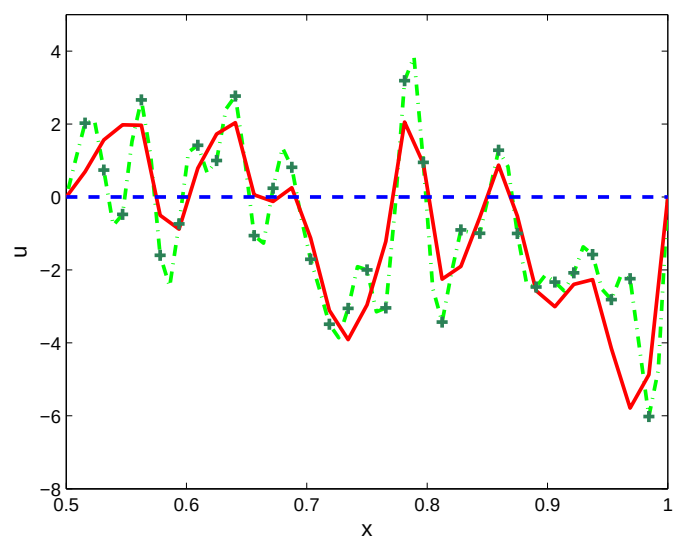
$$\beta_i \begin{cases} \square \\ \square \\ \square \end{cases} \begin{matrix} i < M/\triangleright \\ i = M/\triangleright, \end{matrix}$$

no c o nd e _1 o _e _1 c e nd _1 nce on _e e c e **M**
 _e n _1 e o LAM dpo n .

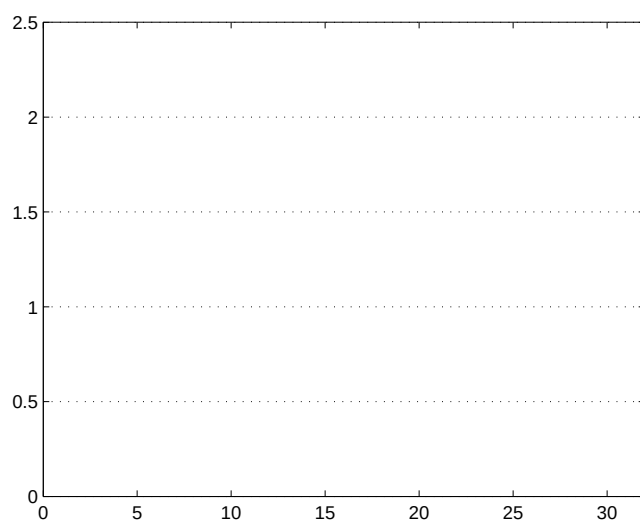
n o e pe _1 en _e on y _n o c _n e _e _1 ¹ e e y _n e e
 ep _e _1 _e e e ence ec o y _e **t** ne co _1 n on o
 ne e _e coe _c en one nd en _1 e **K** , **?** , , ,

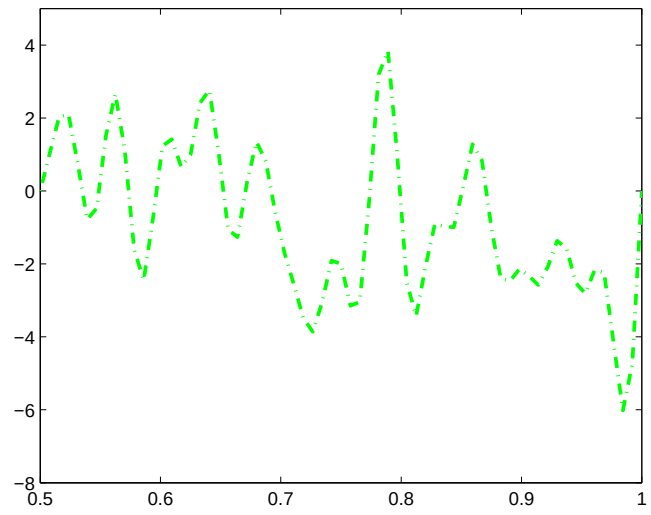






(a) Model outputs for the case with Σ_{α}^{-1} .





c ed y d e ence n e o on co p ed o o o $\tilde{\alpha}^{-1}$ c e e
 no c o nd e $\tilde{\alpha}_1$ n co nc on o ze o $\tilde{\alpha}_1$ de o c o nd
 ec o y no ec n po e pec $\tilde{\alpha}_1$ o n y e cep o LBC
 o e e n e e e o $\tilde{\alpha}^{-1}$ c e $\tilde{\alpha}_1$ de n n y
 $\tilde{\alpha}_1$ c o e n o o n een n enced y ze o c o nd
 e o e on

o c e p nce $\tilde{\alpha}^{-1}$ nd $\tilde{\beta}^{-1}$ e o d xpo ze po e
 pec d e e $\tilde{\alpha}_1$ e o po e pec $\tilde{\alpha}_1$ o $\tilde{\alpha}^{-1}$ c e nd o one
 o $\tilde{\alpha}^{-1}$

9.3 More realistic examples with a non-zero background error covariance matrix Σ

in the model, the model error covariance matrix Σ is non-zero. This is because the model is not perfect and there are errors in the model.

The model error covariance matrix Σ is defined as:

$$\Sigma = \mathbf{U}^T \mathbf{X}_j^T \mathbf{R} \mathbf{X}_j \mathbf{U} + \mathbf{N} \mathbf{X}_j^T \mathbf{R} \mathbf{X}_j \mathbf{N} + \mathbf{N} \mathbf{X}_j^T \mathbf{R} \mathbf{X}_j \mathbf{N}.$$

The covariance matrix Σ is defined as the covariance of the model error. It is a symmetric matrix and is non-negative definite. The model error covariance matrix Σ is defined as:

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9.3.1 A background $\mathbf{x}^b$ with no random noise

The model error covariance matrix Σ is defined as the covariance of the model error. It is a symmetric matrix and is non-negative definite. The model error covariance matrix Σ is defined as:

e c o n d e c o y e n e n e d y n n n p e n o d e o d
 o n e n c o n d o n e c o n d e n n e p o e d o L A M d
 n d e n L A M e o o n n o n d y c o n d o n p o d e d o n p e n
 e o o n n e n e n e c o n d e c o y n y e e e p
 e e c o n d p o d e d y p e n o d e a c o e e o o n e
 d o n z e n L A M

y n c o c e o n e n d n o n p e c c e e e
 e o e o n c o n d n d c o n d e c o y o c o p e e c o c e
 o n e c e d e e n c e n n y

e e γ_0^{-1} n o c o n d e n n e c o n c o n A . I e e
 n c e o n e n e α d α_i n d β d β_i e e

$$\begin{array}{l}
 \alpha_i \begin{bmatrix} \square \\ \square \\ \square \end{bmatrix} . \quad i \quad , \dots , \\
 \quad \quad \quad \square \quad . \quad i \quad , \dots , M ,
 \end{array}$$

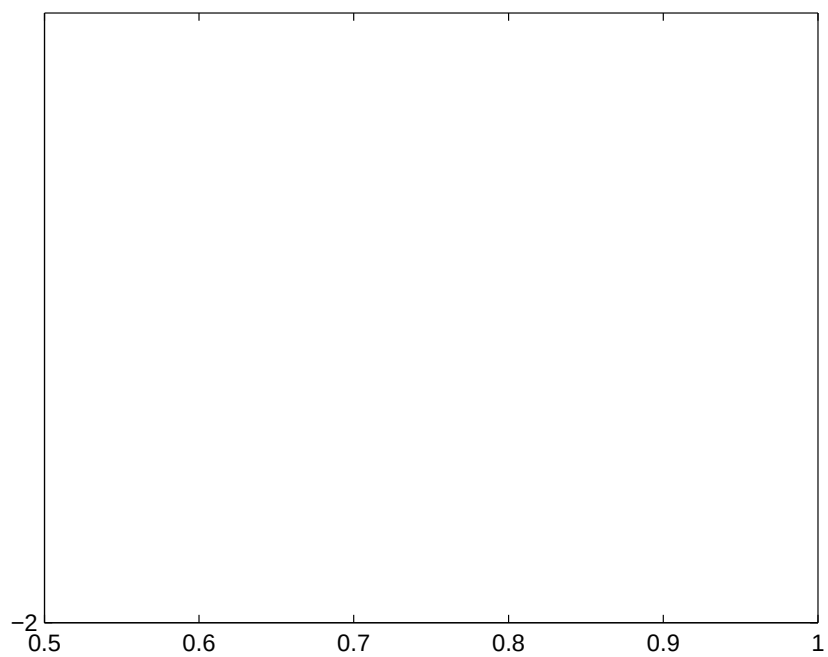
nd

$$\begin{array}{l}
 \beta_i \begin{bmatrix} \square \\ \square \\ \square \\ \square \end{bmatrix} . \quad i \\
 \quad \quad \quad \begin{bmatrix} \square \\ \square \\ \square \end{bmatrix} . \quad i \quad , \dots , \\
 \quad \quad \quad \square \quad . \quad i \quad , \dots , M .
 \end{array}$$

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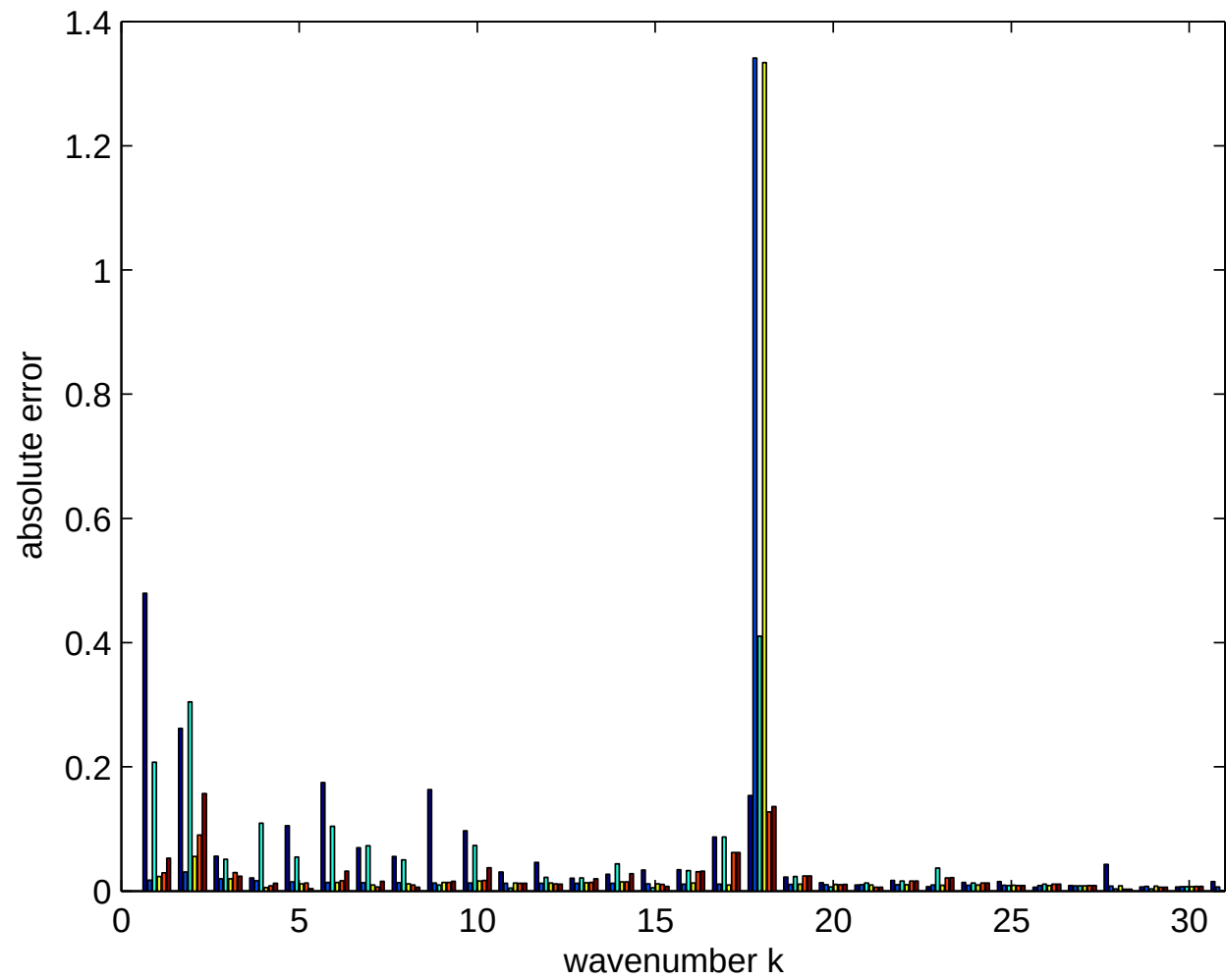
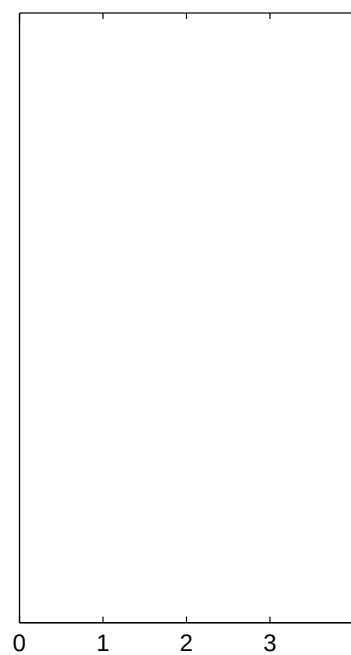


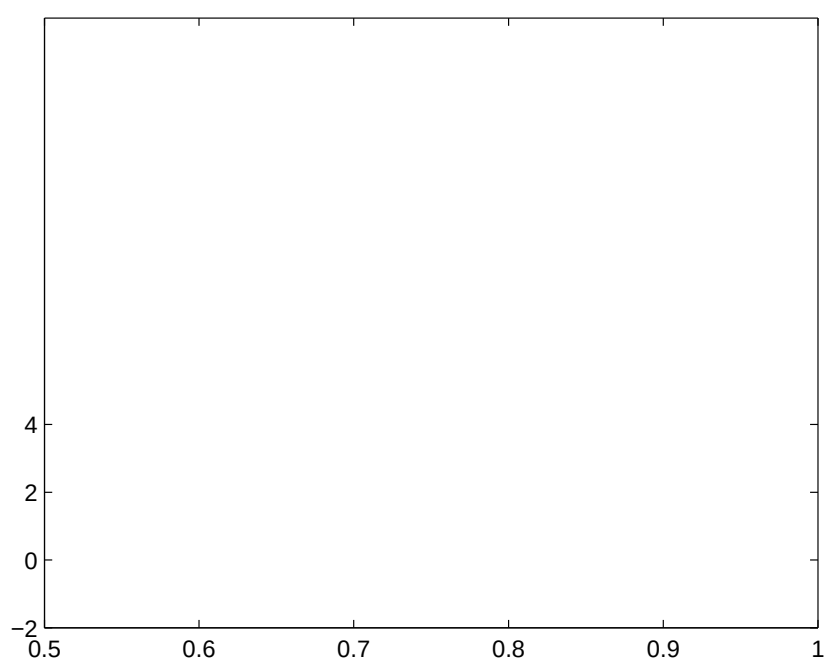
Figure 9.8: Errors in the power spectrum at t



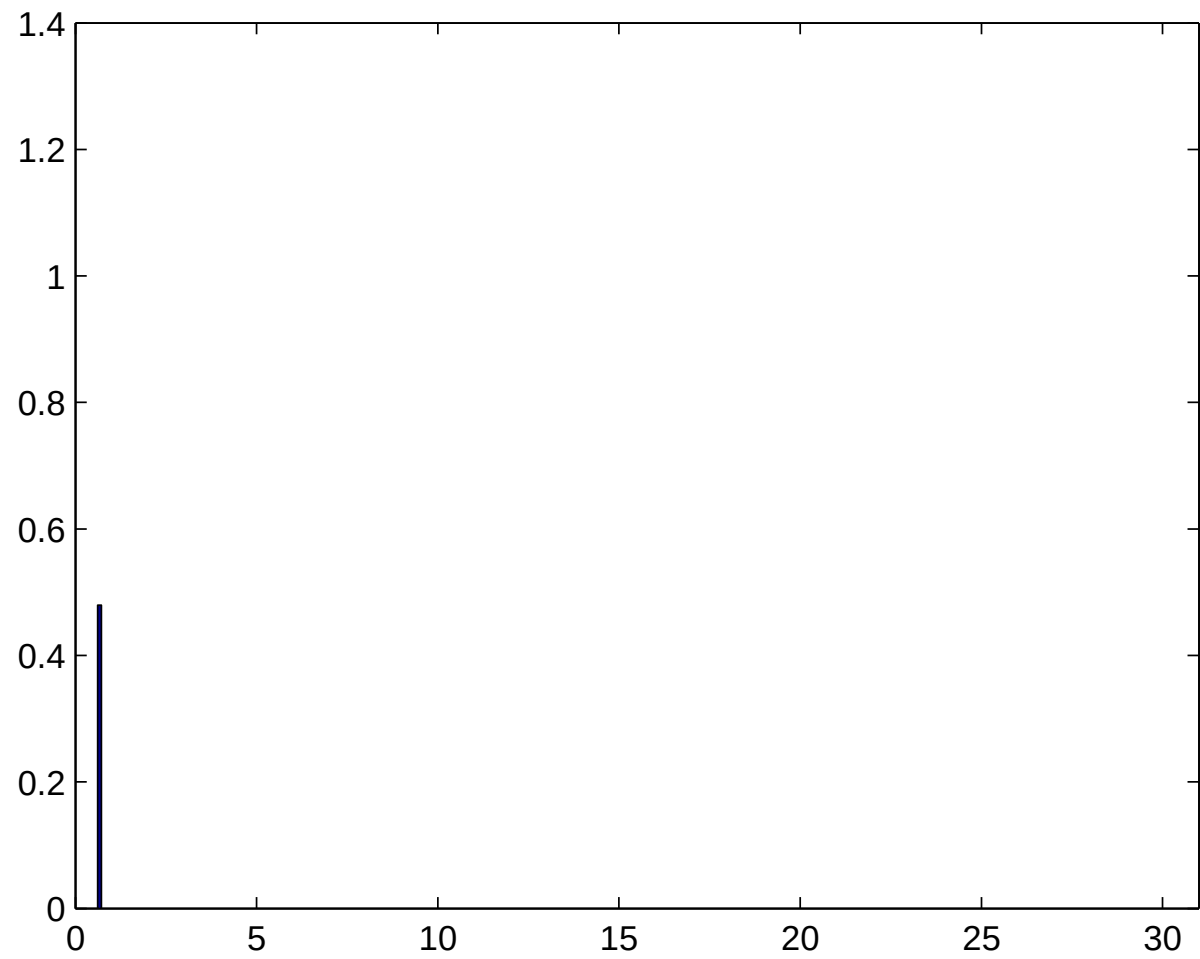
y c o n n e c t i o n s o n n o n c o n d e p o e e o
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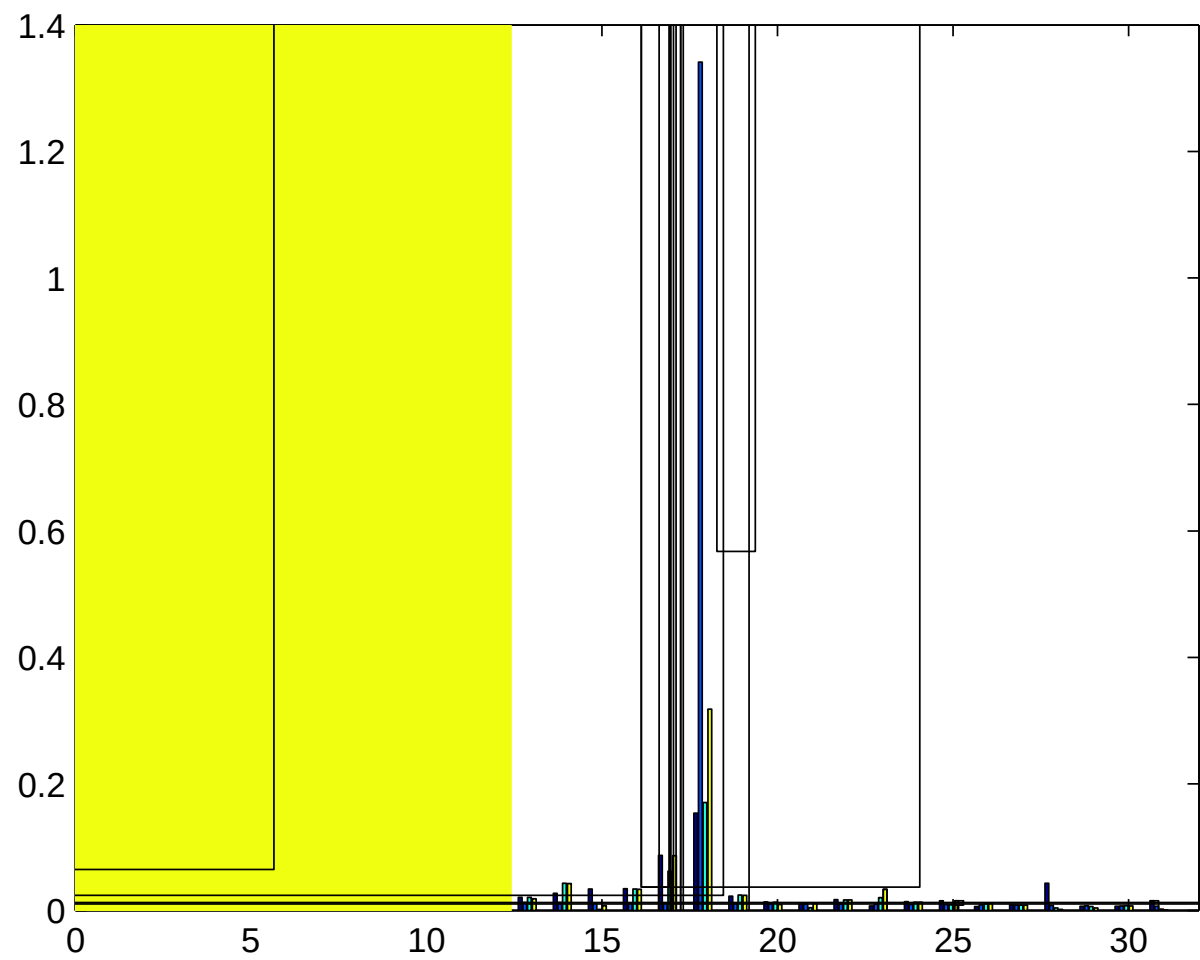
e con de $\frac{1}{2} \cdot 0^1$ c e $\frac{1}{2} \cdot 1^1$ n $\frac{1}{2} \cdot 1^1$ en e o ze o $\frac{1}{2} \cdot 1^1$

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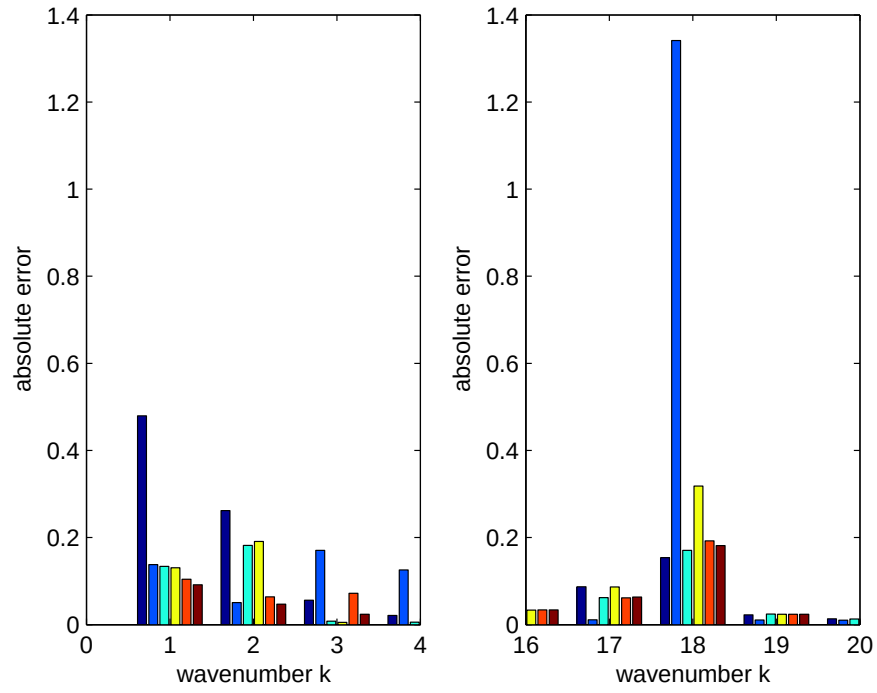


Figure 9.14: Errors in the power spectrum at $t = 0$, a close up of $k = 0, \dots, 4$ and $k = 16, \dots, 20$ for the observations (dark blue), the background (mid blue), the analyses generated with Σ_μ (light blue), Σ_ν (yellow), Σ_ω (orange) and Σ_η (red). A close up of k

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Chapter 10

Conclusions and future work

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By the first step, we find a non-zero element in the field of elements of the ring. This is done by finding a non-zero element in the field of elements of the ring.

10.2 Further work

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