



Scaling Cascades in Complex Systems

# Non-Gaussian data assimilation via a localized hybrid ensemble transform filter

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## Motivation

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## Hybrid Scheme

Ensemble Transform Particle Filter [Reich and Cotter, 2015]

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Example: Single 1D Assimilation Step

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- Likelihood splitting strategies

- Ensemble Inflation and Particle Rejuvenation

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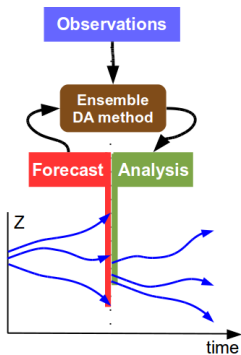
### Spatially extended systems

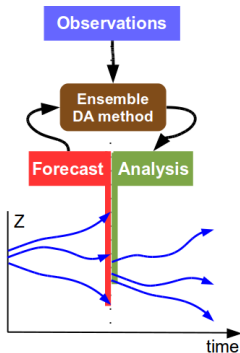
Localization

Example: Lorenz 96 model



# Sequential Data Assimilation Strategies

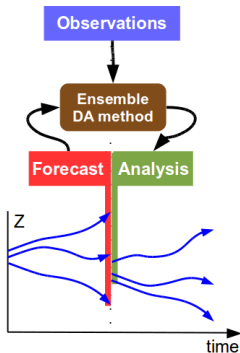




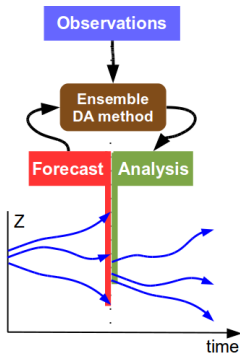
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- + Robust
- + Computationally affordable
- Inconsistent for non-Gaussian PDFs





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- ▶ Particle Filters (Non-parametric Approach)
  - + consistent, suitable for non-Gaussian PDFs
  - Liable to the "Curse of Dimensionality"

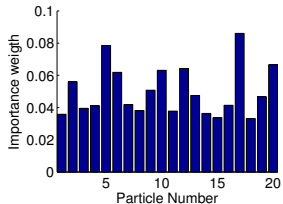


- ▶ Ensemble Kalman Filters (Gaussian Approach)
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- ▶ Particle Filters (Non-parametric Approach)
  - + consistent, suitable for non-Gaussian PDFs
  - Liable to the "Curse of Dimensionality"
- ▶ Hybrid schemes
  - + trade-off between accuracy and stability

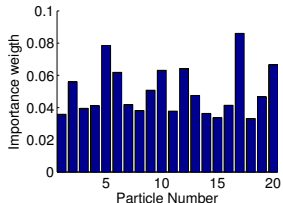


Importance weights:  $w_i = \frac{\exp\left(-\frac{1}{2}(HZ_i^f - y_{\text{obs}})^T R^{-1}(HZ_i^f - y_{\text{obs}})\right)}{\sum_{j=1}^M \exp\left(-\frac{1}{2}(HZ_j^f - y_{\text{obs}})^T R^{-1}(HZ_j^f - y_{\text{obs}})\right)}$  (1)

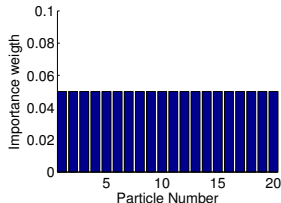
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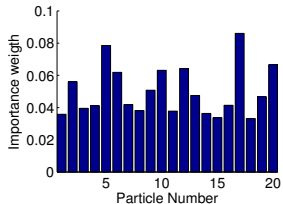
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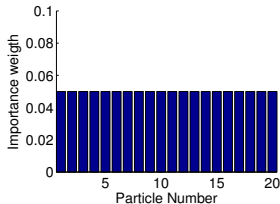
Optimal  
Coupling  
 $T^*$



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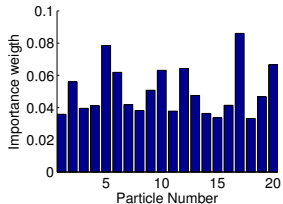
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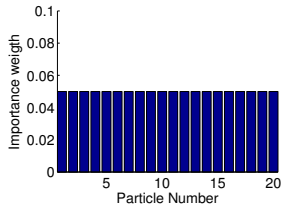
$T^* : \{t_{ij}^* \geq 0\}$  is a linear transformation:

$$z_j^a = M \sum_{i=1}^M z_i^f t_{ij}^* \quad (2)$$

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$T^* : \{t_{ij}^* \geq 0\}$  is a linear transformation:

$$z_j^a = M \sum_{i=1}^M z_i^f t_{ij}^* \quad (2)$$

which minimizes the cost function:

$$J(\{t_{ij}\}) = \sum_{i,j=1}^M t_{ij} \|z_i^f - z_j^f\|^2 \quad (3)$$





## Likelihood function splitting

$\pi_Y(y_{\text{obs}}|Z) \propto$

$$\exp\left(-\frac{\alpha}{2} (HZ - y_{\text{obs}})^T R^{-1} (HZ - y_{\text{obs}})\right) \times \\ \exp\left(-\frac{1-\alpha}{2} (HZ - y_{\text{obs}})^T R^{-1} (HZ - y_{\text{obs}})\right)$$

with **bridging parameter**  $\alpha \in [0, 1]$

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$\Rightarrow$  ETPF

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$\Rightarrow$  EnKF,  
ETKF,

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ESRF, ...

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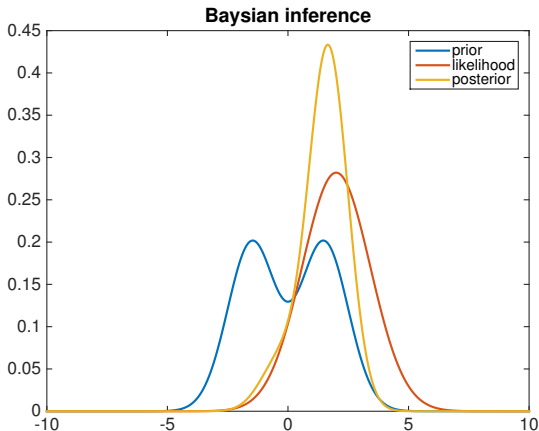
with **bridging parameter**  $\alpha \in [0, 1]$

## Related work

Ensemble Kalman Particle Filter (EKPF) [Frei and Künsch, 2013]:  
bridges the EnKF with perturbed observations and a SIR particle filter.

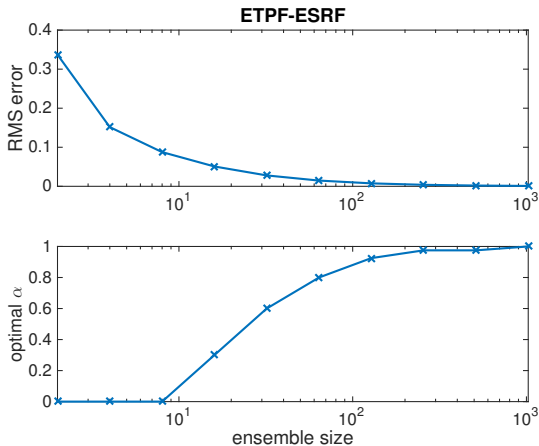


Bayesian Inference  
for bimodal prior  
and  
Gaussian likelihood



# Example: Single 1D Assimilation Step

ETPF-ESRF  
performance vs  
ensemble size  
for optimally chosen  
bridging parameter  
( $\alpha = 0$ : EnKF  
 $\alpha = 1$ : ETPF)









- ▶ **Fixed:**  
keeping bridging parameter constant
  - ▶  $\alpha = 0 \Rightarrow$  Pure Kalman Filter

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- ▶ **Adaptive:**  
keeping ETPF effective sample size

$$M_{\text{eff}}^{\text{ETPF}}(\alpha) := \frac{1}{\sum_{i=1}^M w_i(\alpha)^2}$$

constant

$$M_{\text{eff}}^{\text{ETPF}}(\alpha) = \theta M \tag{4}$$

- ▶  $\theta = 0 \Rightarrow \alpha = 1$  (pure PF)

## Likelihood splitting strategies

- ▶ **Fixed:**  
keeping bridging parameter constant
  - ▶  $\alpha = 0 \Rightarrow$  Pure Kalman Filter
  - ▶  $\alpha = 1 \Rightarrow$  Pure Particle Filter
- ▶ **Adaptive:**  
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$$M_{\text{eff}}^{\text{ETPF}}(\alpha) := \frac{1}{\sum_{i=1}^M w_i(\alpha)^2}$$

constant

$$M_{\text{eff}}^{\text{ETPF}}(\alpha) = \theta M \quad (4)$$

- ▶  $\theta = 0 \Rightarrow \alpha = 1$  (pure PF)
- ▶  $\theta = 1 \Rightarrow \alpha = 0$  (pure EnKF)







In order to prevent

- ▶ Ensemble under-dispersion
- ▶ Particle degeneracy

**Particle rejuvenation** is applied to the analysis ensemble:

$$z_j^a \rightarrow z_j^a + \sum_{i=1}^M (z_i^f - \bar{z}^f) \frac{\beta \xi_{ij}}{\sqrt{M-1}} \quad (5)$$

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- ▶  $\beta$ : Rejuvenation parameter
- ▶  $\xi_{ij}$ 's: i.i.d. Gaussian random variables with mean zero and variance one
- ▶  $\sum_{j=1}^M \xi_{ij} = 0$  so as to preserve the ensemble mean

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**Non-spatially extended systems**

- Likelihood splitting strategies
- Ensemble Inflation and Particle Rejuvenation
- Example: Lorenz 63 model**

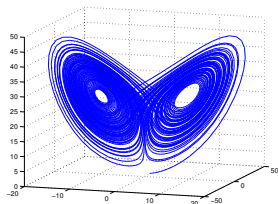
Spatially extended systems

- Localization
- Example: Lorenz 96 model

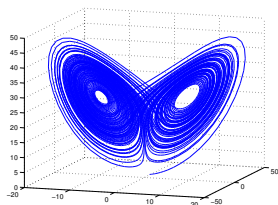
Conclusions and Prospect

## Example: Lorenz 63 model

$$\begin{aligned}\dot{x}_1 &= 10(x_2 - x_1) \\ \dot{x}_2 &= x_1(28 - x_3) - x_2 \\ \dot{x}_3 &= x_1x_2 - \frac{8}{3}x_3\end{aligned}$$



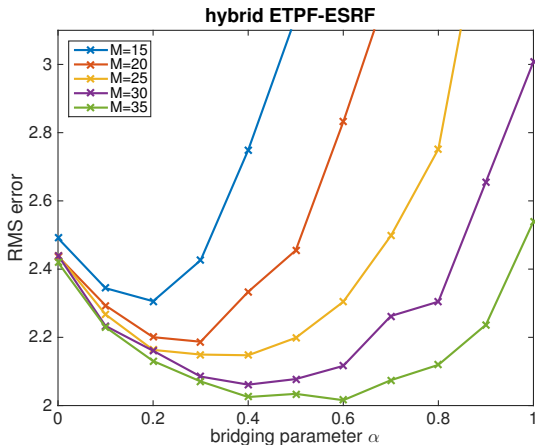
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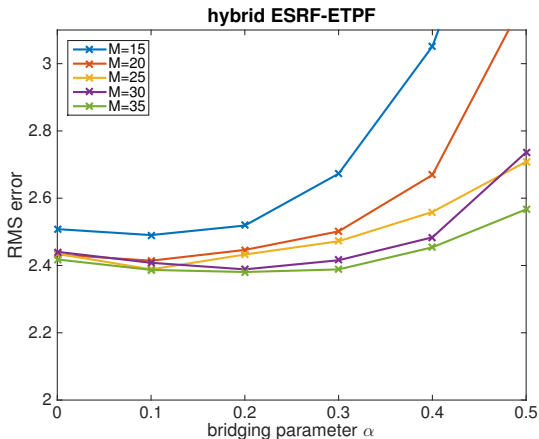
### Perfect model DA experiments:

- ▶ Implicit midpoint method with time step  $\Delta t = 0.01$ .
- ▶  $x_1$  observed every 12 time-steps with error variance  $R = 8$
- ▶ Particle rejuvenation  $\beta = 0.2$
- ▶ 100,000 assimilation cycles
- ▶ OTP solved using FastEMD algorithm

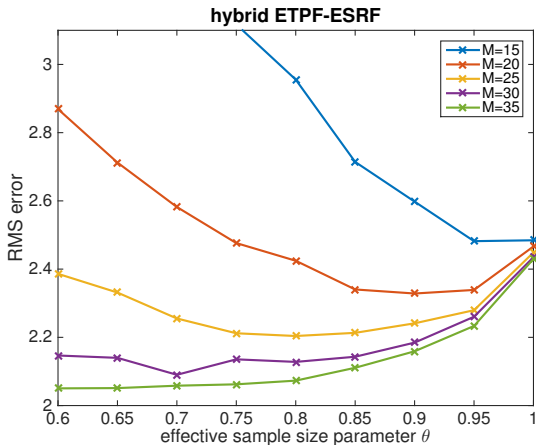
Skill dependence on  
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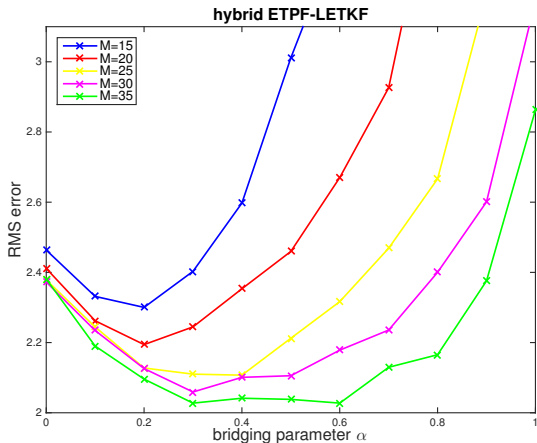


Skill dependence on  
 effective ETPF  
 sample size  
 for different  
 ensemble sizes  
 using adaptive  
 likelihood splitting

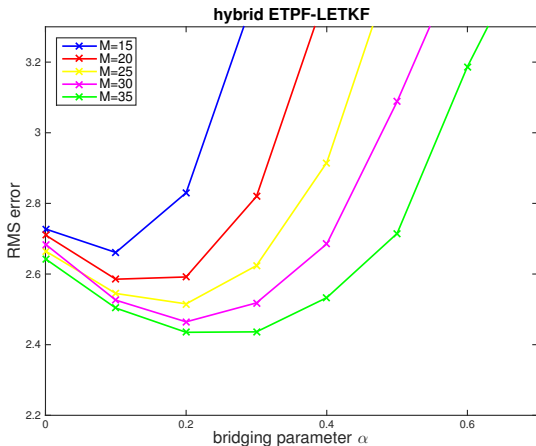




Skill dependence on  
 bridging parameter  
 for different  
 ensemble sizes  
 using fixed  
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 and wrong parameter  
 values  
 (10.2, 28.2, 2.5)



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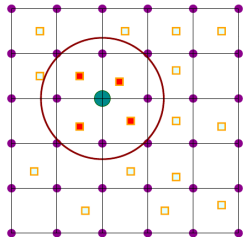
## Conclusions and Prospect



Localized measurement error covariance elements:

$$r_{qq}^{LOC}(x_k) = \frac{r_{qq}}{\rho\left(\frac{\|x_k - x_q\|}{R_{loc}}\right)},$$

with  $\rho$  a compactly supported tempering function, e.g., Gaspari-Cohn function.









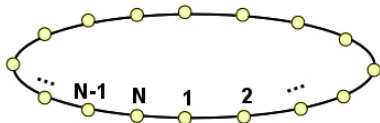


## Example: Lorenz 96 model

$$\dot{x}_j = (x_{j+1} - x_{j-2})x_{j-1} - x_j + F,$$

$$x_j = x_{j+N}$$

where  $F = 8$  and  $N = 40$ .

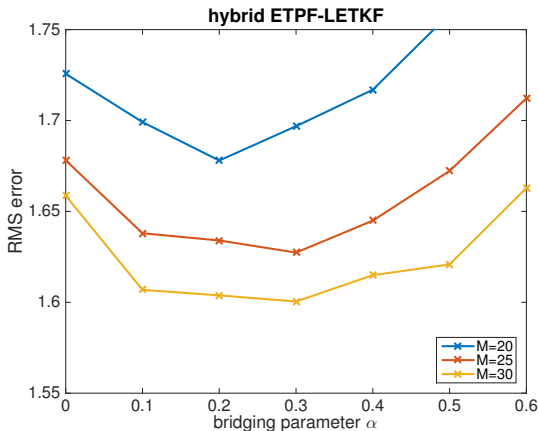


### Perfect model DA experiments:

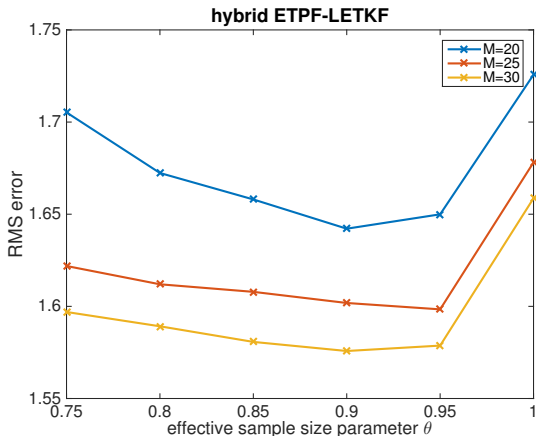
- ▶ Implicit midpoint method with time step  $\Delta t = 0.005$ .
- ▶ Odd variables observed every 22 time-steps
- ▶ Particle rejuvenation  $\beta = 0.2$
- ▶ Localisation radius is  $R_{loc} = 4$
- ▶ 50,000 assimilation cycles
- ▶ OTP solved using FastEMD algorithm

## Example: Lorenz 96 model

Skill dependence on  
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for different  
ensemble sizes  
using fixed  
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Skill dependence on  
effective ETPF  
sample size  
for different  
ensemble sizes  
using adaptive  
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- ▶ Hybrid scheme being currently implemented into the DA system of the Deutsche Wetterdienst

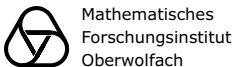


- ▶ Hybrid scheme being currently implemented into the DA system of the Deutsche Wetterdienst
- ▶ Spatial regularity of analysis fields after localisation
- ▶ **Impact of systematic model errors on hybrid scheme**

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- ▶ Spatial regularity of analysis fields after localisation
- ▶ Impact of systematic model errors on hybrid scheme
- ▶ **Hybrid ensemble transform smoother**

-  Cheng, Y. and Reich, S. (2015).  
*Nonlinear Data Assimilation*, chapter Assimilating data into scientific models: An optimal coupling perspective, pages 75–118.  
Springer-Verlag.
-  Chustagulprom, N., Reich, S., and Reinhardt, M. (2015).  
A hybrid ensemble transform filter for nonlinear and spatially extended dynamical systems.  
*submitted, available from ArXiv.*
-  Frei, M. and Künsch, H. R. (2013).  
Bridging the ensemble Kalman and particle filters.  
*Biometrika.*
-  Reich, S. and Cotter, C. (2015).  
*Probabilistic Forecasting and Bayesian Data Assimilation.*  
Cambridge University Press.

# Thanks!



**Data Assimilation: The Mathematics of Connecting Dynamical Systems to Data**  
Organizers: Jana de Wiljes, Potsdam  
Sebastian Reich, Potsdam and Reading  
Andrew Stuart, Warwick  
Date (ID): 15 – 21 May 2016 (1620a)  
Deadline: 13 March 2016

**Mathematical Theory of Evolutionary Fluid-Flow Structure Interactions**  
Organizers: Barbara Kaltenbacher, Klagenfurt  
Igor Kukavica, Los Angeles  
Irena Lasiecka, Memphis  
Roberto Triggiani, Memphis  
Date (ID): 20 – 26 November 2016 (1647b)  
Deadline: 18 September 2016