
TQG NOTES

Linear analysis, marginality numerical models

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Contents

1	Recalls and conventions	3
2	Thermal Rotating Shallow Water (TRSW) model	4
3	Thermal Quasi-Geostrophic (TQG) model	4
3.1	What we are doing ?	4
3.2	The system for $\bar{\psi} = -\bar{U}.y$ and $\bar{\Theta} = M^2.y$	5
3.2.1	Linearisation	6
3.2.2	Wave hypothesis	6
3.2.3	Solving for $\Theta = 0$	8
3.2.4	Solving for $\Theta \neq 0$	8
3.2.5	Verification of the solution	9
3.2.6	Growth rate (I) when β is large	10
3.2.7	Limits study of the growth rate	11
3.2.8	Marginality : when we are very close to the Non-Linear bound	12
3.2.9	Growth rate (II)	14
3.3	The system for $\bar{\psi} = f(y)$ and $\bar{\Theta} = M^2.y$	15
3.3.1	Linearisation & wave hypothesis	15
3.3.2	Solving for $\Theta' = 0$	17
3.3.3	Solving for $\Theta' \neq 0$	17
3.3.4	Stability criteria	18
3.4	General equations for the numerical part	18
3.4.1	Set the system	18
3.5	Non-Linearity	19
4	Numerical investigation of the TQG model	20
4.1	TQG Numerical solution	20
4.1.1	Before the numerical analysis	20
4.1.2	The analytical principle of an eigenvalue problem	21
4.1.3	Discretisation	21

4.1.4	Numerical proposition	22
4.1.5	Tools	23
4.2	Non-TQG Numerical solution	25
4.3	Flow stability	26
4.3.1	Linear : 2 cases [A RE REDIGER]	26
4.4	2D TQG numerical model	27
4.4.1	$\Delta x = \Delta y = \Delta h$	28
4.5	Non-Linear TQG model	30
5	Appendix	30
5.1	Validation of TQG_solve_v2_bis_TARANIS.py	30
	References	31

1. Recalls and conventions

**Be very carefull when reading the document : there is a lot of subtils notations :
for instance K_γ^2 and K^2 .**

If you're lost, see the "What we are doing ?" section (page 4).

Sometime in the document we will use $\partial_t, \partial_x, \partial_y$ instead of $\frac{\partial}{\partial t}, \frac{\partial}{\partial x}, \frac{\partial}{\partial y}$ to avoid reading confusions. For the whole document we state here the writing convention in **Tab. 1.**,

	This document	Version 1	Version 2
Vector/Matrix	$\underline{u} / \underline{\underline{A}}$	$\vec{u} / \vec{\vec{A}}$	\mathbf{u} / \mathbf{A}
Divergence	$\text{div } \underline{u}$	$\vec{\nabla} \cdot \vec{u}$	$\nabla \cdot \mathbf{u}$
Gradient	$\underline{\text{grad } u}$	$\overrightarrow{\nabla u}$	$\nabla \mathbf{u}$
Curl	$\underline{\text{curl } u}$	$\vec{\nabla} \wedge \vec{u}$	$\nabla \times \mathbf{u}$
Laplacian	$\text{div } (\underline{\text{grad } u})$	$\vec{\nabla} \cdot (\overrightarrow{\nabla u})$	$\nabla \cdot (\nabla \mathbf{u})$

Tab. 1. Writing conventions for this document. Note that the identity matrix Id is written without the $\underline{\underline{\dots}}$ because it's a remarkable matrix.

For wave hypothesis we shall introduce a quantity λ that can be described with waves with $\omega = c.k$ and k, l the wave number of x, y directions,

$$\lambda = \hat{\lambda} \cdot \exp(i.(k.x + l.y - \omega.t))$$

Subsequently we can introduce the time derivative and also the space derivative of this function,

$$\begin{aligned} \partial_t \lambda &= -i.\omega.\hat{\lambda} \cdot \exp(i.(k.x + l.y - \omega.t)) \\ \partial_x \lambda &= i.k.\hat{\lambda} \cdot \exp(i.(k.x + l.y - \omega.t)) \\ \partial_y \lambda &= i.l.\hat{\lambda} \cdot \exp(i.(k.x + l.y - \omega.t)) \\ \text{div}(\underline{\text{grad } \lambda}) &= (-k^2 - l^2) \cdot \exp(i.(k.x + l.y - \omega.t)) \\ &= -(k^2 + l^2) \cdot \exp(i.(k.x + l.y - \omega.t)) \end{aligned}$$

Generally we will state $\aleph = i.(k.x + l.y - \omega.t)$ that gives $\lambda = \hat{\lambda} \cdot \exp(\aleph)$. And when it's possible, normalise by $\exp(\aleph)$ to avoid reading confusions.

We note also that,

$$\lambda = \mathbf{Re}\left\{\hat{\lambda}.\exp(\mathfrak{N})\right\}$$

$$||\hat{\lambda}|| = ||\lambda||$$

We use the the notation \mathbf{Id} to make appear the identity matrix of $n \times n$ size with $n \in \mathbb{N}$.

$$\mathbf{Id}_{n \times n} = \begin{pmatrix} 1 & 0 & 0 & \cdots & 0 \\ 0 & 1 & & & 0 \\ 0 & & 1 & & 0 \\ \vdots & & & \ddots & \vdots \\ 0 & 0 & 0 & \cdots & 1 \end{pmatrix}_{n \times n}$$

2. Thermal Rotating Shallow Water (TRSW) model

- History of the TRSW and TQG equations (primitive thermal model) : [Ripa, 1991] [Ripa, 1993] [Ripa, 1995]
- Other usefull articles : [Gouzien et al., 2017] ; the [Lahaye et al., 2020] solves and propose visualisation of some TQG solution.

The Thermal Shallow Water model can be founded in the Zeitlin's book [Zeitlin, 2018] (Chapter 14 page 409) and also Rouillet's notes [Rouillet, 2021] is defined by,

$$\boxed{\frac{\partial \underline{u}}{\partial t} + \underline{u}.\mathbf{grad} \underline{u} = -\frac{g}{2.h}.\mathbf{grad}(\Theta.h)} \quad (1a)$$

$$\boxed{\frac{\partial h}{\partial t} + \underline{u}.\mathbf{div}(h.\underline{u}) = 0} \quad (1b)$$

$$\boxed{\frac{\partial \Theta}{\partial t} + \underline{u}.\mathbf{grad} \Theta = 0} \quad (1c)$$

Where the Temperature Θ modifies the "classical" version of the shallow water model. We note that in our case the conservation of the temperature over time $\frac{D\Theta}{Dt} = 0$ is true. We assume a 1 layer model where there is no variation of the velocity following z : $\frac{\partial \underline{u}}{\partial z} = 0$ and so we get rid of the thermal wind balance.

We can cite also [Wang and Xu, 2024] that provides a good statement of the TRSW and TQG models. For a complete description we can see also [Warneford and Dellar, 2013].

3. Thermal Quasi-Geostrophic (TQG) model

The fundamental article that drives a QG analysis is [Flierl et al., 1987].

3.1. What we are doing ?

1. From **page 6** to **page 9** we derive a linear model with a linear $\bar{\psi} = \bar{U}.y$. Note that originally the system is 2D : $J(\psi, \lambda)$ is x, y dependent (λ is a parameter like q or Θ). **The solving with a linear $\bar{\psi} = \bar{U}.y$ gives us a scalar solution of c .** There is no t, x, y dependency anymore because we divide by $i.k(x + y - c.t)$.

That's a linear TQG, scalar model, with a linear $\bar{\psi} = \bar{U}.y$

This part can be done on paper (this document).

2. From **page 20** to **page 25** we discretise the initial TQG problem into a 1D problem. But we conserved the y dependency due to the non-linearity

That's a linear TQG 1D in y model, with a non-linear $\bar{\psi} = f(y)$

This part can be done with `TQG_solve_v2_bis_TARANIS.py`

3. From **page 27** to **page 30** we discretise in 2D the previous model.

That's a linear TQG 2D in x, y model, with a non-linear $\bar{\psi} = f(y)$

This part can be done with `TQG_solve_v3_bis_JULIE.py`

3.2. The system for $\bar{\psi} = -\bar{U}.y$ and $\bar{\Theta} = M^2.y$

We recall that the streamfunction ψ is defined as $\frac{\partial \psi}{\partial x} = v$ and $-\frac{\partial \psi}{\partial y} = u$. We consider the QG 1 layer Potential vorticity and it's conservation,

$$\beta.y + \mathbf{div}(\mathbf{grad} \psi) - \frac{\psi}{R_d^2} = q \quad (2a)$$

$$\frac{\partial q}{\partial t} + J(\psi, q) = 0 \quad (2b)$$

If we force the system with a parameter such like the buoyancy b or the Temperature Θ we can write a new PV conservation. We shall now introduce also the conservation of this quantity in the QG equations,

$$\beta.y + \mathbf{div}(\mathbf{grad} \psi) - \frac{\psi}{R_d^2} = q \quad (3a)$$

$$\frac{\partial q}{\partial t} + J(\psi, q - \Theta) = 0 \quad (3b)$$

$$\frac{\partial \Theta}{\partial t} + J(\psi, \Theta) = 0 \quad (3c)$$

Here we don't introduce the temperature's dissipation for this model. And we note also that the Jacobian of a function $g(x, y)$ is equivalent to $J(\psi, g) = \underline{u}.\mathbf{grad} g = \frac{\partial \psi}{\partial x} \cdot \frac{\partial g}{\partial y} - \frac{\partial g}{\partial x} \cdot \frac{\partial \psi}{\partial y}$.

3.2.1. Linearisation

We start by the linearisation of the previous set of equation. We introduce the quantities $q = \bar{q} + q'$, $\psi = \bar{\psi} + \psi'$ and $\Theta = \bar{\Theta} + \Theta'$. We recall that all time derivatives of means \bar{q} , $\bar{\psi}$, $\bar{\Theta}$ are equals to 0. Let's do it for the equation with Θ (it will be exactly the same developpement for the $q - \Theta$ equation). We shall now introduce $\bar{\psi} = -\bar{U}.y$, we assume $\bar{q} = \left(\frac{\bar{U}}{R_d^2} + \beta\right).y$ and a $\bar{\Theta} = M^2.y$ with $M^2 = \frac{db}{dz}$ or $\frac{d\Theta}{dz}$ a constant. From (3c), we immediatly see that,

$$\frac{\partial(\bar{\Theta} + \Theta')}{\partial t} + J(\bar{\psi} + \psi', \bar{\Theta} + \Theta') = 0$$

$$\cancel{\frac{\partial \bar{\Theta}}{\partial t}} + \frac{\partial \Theta'}{\partial t} + J(\bar{\psi}, \bar{q}) + J(\bar{\psi}, q') + J(\psi', \bar{q}) + \cancel{J(\psi', q')} \stackrel{\text{Small}}{=} 0$$



Note also that

Taking into account that $\bar{\psi} = -\bar{U}.y$ and $\bar{\Theta} = M^2.y$ we see that the Jacobian of the 2 means is 0 because,

$$J(\bar{\psi}, \bar{\Theta}) = \partial_x \bar{\psi} \cdot \partial_y \bar{\Theta} - \partial_x \bar{\Theta} \cdot \partial_y \bar{\psi}$$

$$= \partial_x (-\bar{U}.y) \cdot \partial_y (M^2.y) - \partial_x (M^2.y) \cdot \partial_y (-U.y) \stackrel{0}{=} 0$$

$$= 0$$

So if we detail the equation above we get,

$$\frac{\partial \Theta'}{\partial t} + \cancel{J(\bar{\psi}, \bar{\Theta})} + J(\bar{\psi}, \Theta') + J(\psi', \bar{\Theta}) + \cancel{J(\psi', \Theta')} \stackrel{\text{Small}}{=} 0$$

$$\frac{\partial \Theta'}{\partial t} + J(\bar{\psi}, \Theta') + J(\psi', \bar{\Theta}) = 0$$

The same result can be founded with the equation (3b) : $\frac{\partial q}{\partial t} + J(\psi, q - \Theta) = 0$ (we just have to replace Θ by $q - \Theta$ and as long as $\bar{\Theta}, \bar{q} \propto (t, x)$ but $\propto y$ there is no risk about doing that) and we get the linearised equations,

$$\boxed{\frac{\partial q'}{\partial t} + J(\bar{\psi}, q' - \Theta') + J(\psi', \bar{q} - \bar{\Theta}) = 0} \quad (4a)$$

$$\boxed{\frac{\partial \Theta'}{\partial t} + J(\bar{\psi}, \Theta') + J(\psi', \bar{\Theta}) = 0} \quad (4b)$$

3.2.2. Wave hypothesis

We will start the with 2 equation (4a) and (4b) to find the dispersion relation c of the system.

Step 1 : $q - \Theta$

$$\frac{\partial q'}{\partial t} + \cancel{\partial_x \bar{\psi} \cdot \partial_y (q' - \Theta')} - \partial_x (q' - \Theta') \cdot \partial_y \bar{\psi} + \partial_x \psi' \cdot \partial_y (\bar{q} - \bar{\Theta}) - \cancel{\partial_x (\bar{q} - \bar{\Theta}) \cdot \partial_y \psi'} = 0$$

$$\frac{\partial q'}{\partial t} - \partial_x (q' - \Theta') \cdot \partial_y \bar{\psi} + \partial_x \psi' \cdot \partial_y (\bar{q} - \bar{\Theta}) = 0$$

We replace some values with $q' = \text{div}(\underline{\text{grad}} \psi') - \frac{\psi'}{R_d^2} + \beta.y$, that will allows us to make the wave hypothesis only on ψ and Θ ,

$$\begin{aligned} \frac{\partial}{\partial t} \cdot \left[\text{div}(\underline{\text{grad}} \psi') - \frac{\psi'}{R_d^2} + \beta.y \right] - \partial_x \left(\left[\text{div}(\underline{\text{grad}} \psi') - \frac{\psi'}{R_d^2} + \beta.y \right] - \Theta' \right) \cdot \partial_y \cdot (-\bar{U}.y) \\ + \partial_x \psi' \cdot \partial_y \cdot \left(\left(\frac{\bar{U}}{R_d^2} + \beta \right) \cdot y - M^2.y \right) = 0 \\ \frac{\partial}{\partial t} \cdot \left[\text{div}(\underline{\text{grad}} \psi') - \frac{\psi'}{R_d^2} + \beta.y \right] + \partial_x \left(\left[\text{div}(\underline{\text{grad}} \psi') - \frac{\psi'}{R_d^2} + \beta.y \right] - \Theta' \right) \cdot \bar{U} \\ + \partial_x \psi' \cdot \left(\frac{\bar{U}}{R_d^2} + \beta - M^2 \right) = 0 \end{aligned}$$

We introduce the folowing wave-hypothesis : $\psi' = \hat{\psi}' \cdot \exp(\aleph)$ with $\aleph = i.(k.x + l.y - \omega.t)$, the same wave hypothesis can be done for Θ' (note that $c = \frac{\omega}{k}$), (we have divided by $\exp(\aleph)$ because it should have been too heavy to write) we note that,

$$\begin{aligned} -i.\omega. \left[- \left(k^2 + l^2 + \frac{1}{R_d^2} \right) \right] \cdot \hat{\psi}' + i.k. \left(\left[- (k^2 + l^2 + \frac{1}{R_d^2}) \cdot \hat{\psi}' \right] - i.k.\hat{\Theta}' \right) \cdot \bar{U} \\ + i.k.\hat{\psi}' \cdot \left(\frac{\bar{U}}{R_d^2} + \beta - M^2 \right) = 0 \quad || \times \frac{1}{i.k} \\ -c. \left[- \left(k^2 + l^2 + \frac{1}{R_d^2} \right) \right] \cdot \hat{\psi}' - \left(k^2 + l^2 + \frac{1}{R_d^2} \right) \cdot \hat{\psi}' \cdot \bar{U} - \hat{\Theta}' \cdot \bar{U} \\ + \hat{\psi}' \cdot \left(\frac{\bar{U}}{R_d^2} + \beta - M^2 \right) = 0 \end{aligned}$$

We introduce $K_\gamma^2 = k^2 + l^2 + \frac{1}{R_d^2}$ and $\alpha = \beta - M^2 + \frac{\bar{U}}{R_d^2}$,

$$\begin{aligned} -c. \left[-K_\gamma^2 \cdot \hat{\psi}' \right] - K_\gamma^2 \cdot \hat{\psi}' \cdot \bar{U} - \hat{\Theta}' \cdot \bar{U} + \hat{\psi}' \cdot \alpha = 0 \\ [- (U - c) \cdot K_\gamma^2 + \alpha] \cdot \hat{\psi}' - \bar{U} \cdot \hat{\Theta}' = 0 \end{aligned}$$

Step 2 : Θ

$$\begin{aligned} \frac{\partial \Theta'}{\partial t} + \partial_x \bar{\psi} \cdot \partial_y \cdot \Theta' - \partial_x \Theta' \cdot \partial_y \cdot \bar{\psi} + \partial_x \psi' \cdot \partial_y \bar{\Theta} - \partial_x \bar{\Theta} \cdot \partial_y \psi' = 0 \\ \frac{\partial \Theta'}{\partial t} + \cancel{\partial_x (-\bar{U}.y) \cdot \partial_y \cdot \Theta'} \xrightarrow{0} - \partial_x \Theta' \cdot \partial_y \cdot (-\bar{U}.y) + \partial_x \psi' \cdot \partial_y (M^2.y) - \cancel{\partial_x (M^2.y) \cdot \partial_y \psi'} \xrightarrow{0} = 0 \\ \frac{\partial \Theta'}{\partial t} - \partial_x \Theta' \cdot \partial_y \cdot (-\bar{U}.y) + \partial_x \psi' \cdot \partial_y (M^2.y) = 0 \\ \frac{\partial \Theta'}{\partial t} + \partial_x \Theta' \cdot \bar{U} + \partial_x \psi' \cdot M^2 = 0 \end{aligned}$$

The same wave hypothesis can be done for Θ' (note that $c = \frac{\omega}{k}$),

$$\begin{aligned}
\frac{\partial}{\partial t}.\Theta' \cdot \mathbf{exp}(\aleph) + \partial_x.\Theta' \cdot \mathbf{exp}(\aleph).\bar{U} + \partial_x\psi' \cdot \mathbf{exp}(\aleph).M^2 &= 0 \\
-i.\omega.\hat{\Theta}' \cdot \mathbf{exp}(\aleph) + i.k.\hat{\Theta}' \cdot \mathbf{exp}(\aleph).\bar{U} + i.k.\hat{\psi}' \cdot \mathbf{exp}(\aleph).M^2 &= 0 \quad \left\| \times \frac{1}{i.k.\mathbf{exp}(\aleph)} \right. \\
-\frac{\omega}{k}.\hat{\Theta}' + \hat{\Theta}'.\bar{U} + \hat{\psi}'.M^2 &= 0 \\
(\bar{U} - c).\hat{\Theta}' + M^2.\hat{\psi}' &= 0
\end{aligned}$$

So the 2 equations are,

$$\boxed{\left[-(\bar{U} - c).K_\gamma^2 + \alpha \right].\hat{\psi}' - \bar{U}.\hat{\Theta}' = 0} \tag{5a}$$

$$\boxed{(\bar{U} - c).\hat{\Theta}' + \hat{\psi}'.M^2 = 0} \tag{5b}$$

3.2.3. Solving for $\Theta = 0$

We suppose $\Theta = 0, \Theta' = 0, \bar{\Theta} = 0$, so the previous set of equations (5a) and (5b) becomes,

$$\begin{aligned}
\left[-(\bar{U} - c).K_\gamma^2 + \alpha \right].\hat{\psi}' - \bar{U}.\hat{\Theta}' &= 0 \\
(\bar{U} - c).\hat{\Theta}' + \hat{\psi}'.M^2 &= 0
\end{aligned}$$

ψ' can't be 0, so we deduce that $M^2 = 0$, we recall that $\alpha = \beta - M^2 + \frac{\bar{U}}{R_d^2}$ and so,

$$\begin{aligned}
\left[-(\bar{U} - c).K_\gamma^2 + \alpha \right].\hat{\psi}' - \bar{U}.\hat{\Theta}' &= 0 \\
\left[-(\bar{U} - c).K_\gamma^2 + \beta + \frac{\bar{U}}{R_d^2} \right].\hat{\psi}' &= 0 \\
-(\bar{U} - c).K_\gamma^2 &= -\left(\beta + \frac{\bar{U}}{R_d^2} \right)
\end{aligned}$$

Which is the dispersion relation for a neutral Rossby wave with $K_\gamma^2 = k^2 + l^2 + \frac{1}{R_d^2}$.

$$\boxed{c = \bar{U} - \frac{\left(\beta + \frac{\bar{U}}{R_d^2} \right)}{K_\gamma^2}} \tag{6}$$

3.2.4. Solving for $\Theta \neq 0$

Now we restart from our system presented in (5a) and (5b) and if $\Theta, \Theta', \bar{\Theta} \neq 0$ we can solve a 2D matrix system (we recall that we set $\bar{\Theta} = M^2.y$). From equations,

$$\begin{aligned}
\left[-(\bar{U} - c).K_\gamma^2 + \alpha \right].\hat{\psi}' - \bar{U}.\hat{\Theta}' &= 0 \\
(\bar{U} - c).\hat{\Theta}' + \hat{\psi}'.M^2 &= 0
\end{aligned}$$

We get,

$$\underbrace{\begin{pmatrix} -(\bar{U} - c).K_\gamma^2 + \alpha & -\bar{U} \\ M^2 & \bar{U} - c \end{pmatrix}}_{\underline{\underline{A}}} \times \begin{pmatrix} \hat{\psi}' \\ \hat{\Theta}' \end{pmatrix} = \begin{pmatrix} 0 \\ 0 \end{pmatrix}$$

This system $\underline{\underline{A}} \times \underline{v} = \underline{0}$ can be solved by using the null-determinant method,

$$\begin{aligned} \det(\underline{\underline{A}}) &= 0 \\ \left[-(\bar{U} - c).K_\gamma^2 + \alpha \right] \cdot [\bar{U} - c] + M^2 \cdot \bar{U} &= 0 \\ -\left[\bar{U}^2 - 2\bar{U}.c + c^2 \right] \cdot K_\gamma^2 + \alpha \cdot [\bar{U} - c] + M^2 \cdot \bar{U} &= 0 \\ -K_\gamma^2(\bar{U} - c)^2 + \alpha \cdot [\bar{U} - c] + M^2 \cdot \bar{U} &= 0 \end{aligned}$$

The previous equation is a polynomial 2nd order equation : to make it more visible let us introduce $R = \bar{U} - c$, we see

$$\boxed{-K_\gamma^2.R^2 + \alpha.R + M^2.\bar{U} = 0} \quad (7)$$

The coefficients of the equation in $\underline{X} = \bar{U} - c$, are $k_1 = -K_\gamma^2, k_2 = \alpha, k_3 = M^2.\bar{U}$ so the discriminant is $\Delta = k_2^2 - 4.k_1.k_3$,

$$\Delta = \alpha^2 + 4.K_\gamma^2.M^2.\bar{U} > 0$$

And the solutions are, with $\alpha = \beta - M^2 + \frac{\bar{U}}{R_d^2}$ and $K_\gamma^2 = k^2 + l^2 + \frac{1}{R_d^2}$

$$\begin{aligned} \bar{U} - c &= -\frac{b}{2.a} \pm \frac{\sqrt{\Delta}}{2.a} \\ &= -\frac{\alpha}{-2.K_\gamma^2} \pm \frac{\sqrt{\alpha^2 + 4.K_\gamma^2.M^2.\bar{U}}}{-2.K_\gamma^2} \end{aligned}$$

Now we just expand the coefficients,

$$\boxed{\bar{U} - c = \frac{\beta - M^2 + \frac{\bar{U}}{R_d^2}}{2. \left(k^2 + l^2 + \frac{1}{R_d^2} \right)} \pm \frac{\sqrt{\left(\beta - M^2 + \frac{\bar{U}}{R_d^2} \right)^2 + 4. \left(k^2 + l^2 + \frac{1}{R_d^2} \right). M^2.\bar{U}}}{-2. \left(k^2 + l^2 + \frac{1}{R_d^2} \right)}} \quad (8)$$

3.2.5. Verification of the solution

We are now able to compare this result with the article [[Beron-Vera, 2021](#)] that derives the same kind of problem. To verify that we can set $U_\sigma = -\frac{M^2}{R_d^2}$ so $M^2 = -U_\sigma.R_d^2$ to translate our solution into their solution and note that $|\mathbf{k}|^2 = k^2 + l^2$.

$$\begin{aligned}
\bar{U} - c &= \frac{\beta - M^2 + \frac{\bar{U}}{R_d^2}}{2 \cdot \left(k^2 + l^2 + \frac{1}{R_d^2}\right)} \pm \frac{\sqrt{\left(\beta - M^2 + \frac{\bar{U}}{R_d^2}\right)^2 + 4 \cdot \left(k^2 + l^2 + \frac{1}{R_d^2}\right) \cdot M^2 \cdot \bar{U}}}{-2 \cdot \left(k^2 + l^2 + \frac{1}{R_d^2}\right)} \\
&= \frac{\beta + U_\sigma \cdot R_d^2 + \frac{\bar{U}}{R_d^2}}{2 \cdot \left(|\mathbf{k}|^2 + \frac{1}{R_d^2}\right)} \pm \frac{\sqrt{\left(\beta + U_\sigma \cdot R_d^2 + \frac{\bar{U}}{R_d^2}\right)^2 - 4 \cdot \left(|\mathbf{k}|^2 + \frac{1}{R_d^2}\right) \cdot U_\sigma \cdot \bar{U} \cdot R_d^2}}{-2 \cdot \left(|\mathbf{k}|^2 + \frac{1}{R_d^2}\right)} \\
&= \frac{\beta \cdot R_d^2 + U_\sigma + \bar{U}}{2 \cdot |\mathbf{k}|^2 \cdot R_d^2 + 2} \pm \frac{\sqrt{\left(\beta \cdot R_d^2 + U_\sigma + \bar{U}\right)^2 - 4 \cdot \left(|\mathbf{k}|^2 \cdot R_d^2 + 1\right) \cdot U_\sigma \cdot \bar{U} \cdot R_d^2}}{-2 \cdot |\mathbf{k}|^2 \cdot R_d^2 + 2}
\end{aligned}$$

After that we just have to multiply by -1 to convert $c - \bar{U}$ in the article into $\bar{U} - c$ for us. **Both solutions are equivalent.**

3.2.6. Growth rate (I) when β is large

We know, from the equation (7), that the discriminant $\Delta = b^2 - 4 \cdot a \cdot c$ can be written,

$$\begin{aligned}
\Delta &= \alpha^2 + 4 \cdot K_\gamma^2 \cdot M^2 \cdot \bar{U} \\
&= \left(\beta - T_0 + \frac{\bar{U}}{R_d^2}\right)^2 + 4 \cdot K_\gamma^2 \cdot M^2 \cdot \bar{U}
\end{aligned}$$

That can be re-written with $\alpha = \beta - T_0 + \frac{\bar{U}}{R_d^2}$. We shall now assume that $\beta \gg$ to other terms so we can simplify it. And assuming $M^2 = T_0$ we get

$$\Delta = \beta^2 + 4 \cdot K_\gamma^2 \cdot T_0 \cdot \bar{U}$$

A critical value is reached at $\Delta = 0$ so we get the following value of K_γ^2 that we call $K_{\gamma_c}^2$,

$$\boxed{K_{\gamma_c}^2 = -\frac{\beta^2}{4 \cdot T_0 \cdot \bar{U}}} \quad (9)$$

This last equation will be the mean state of K_γ^2 when assuming $K_\gamma = K_{\gamma_c} + K_\gamma'$

When $\Delta < 0$ we get $K_\gamma^2 > -\frac{\beta^2}{4 \cdot T_0 \cdot \bar{U}}$ and the roots are basically

$$\begin{aligned}
c &= -\frac{b}{2 \cdot a} \pm \frac{\sqrt{-\Delta}}{2 \cdot a} \\
0 < \text{Im}\{c\} &= \frac{\sqrt{-\Delta}}{2 \cdot a}
\end{aligned}$$

We want the Imaginary part of the roots of c then we multiply by k to find the imaginary part of $\sigma = \sigma_i$

$$\sigma_i = \frac{\sqrt{-\Delta}}{2 \cdot K_\gamma^2} \cdot k$$

We know that $K_\gamma^2 = k^2 + l^2 + \frac{1}{R_d^2}$ and we choose to set $\frac{1}{R_d^2} = 0$ so we get K^2 instead of K_γ^2 ,

$$\boxed{\sigma_i = \frac{\sqrt{-\Delta}}{2 \cdot K^2} \cdot k} \quad (10)$$

Here we set $K = K_c + K'$ so in the "normal" discriminant,

$$\begin{aligned}
\Delta &= \beta^2 + 4.K_\gamma^2.T_0.\overline{U} \\
&= \beta^2 + 4.(K_{\text{critical}} + K')^2.T_0.\overline{U} \\
&= \beta^2 + 4.T_0.\overline{U}.(K_{\text{critical}}^2 + 2.K_{\text{critical}}.K' + \overset{\text{small}}{K'^2})
\end{aligned}$$

(By definition ?)

$$\Delta = 2.K_c.K'$$

We re-write the growth rate σ_i , and we also consider that $K = k = k_{\text{critical}} + k'$

$$\boxed{\sigma_i = \frac{\sqrt{-2.K_c.k'}}{2.K_c}.k} \quad (11)$$

3.2.7. Limits study of the growth rate

We know now that our growth rate σ_i can be written as,

$$\begin{aligned}
\sigma_i &= \frac{\sqrt{-2.K_c.k'}}{2.K_c}.k \quad \text{or} \quad \sigma_i = \frac{\sqrt{\frac{\beta^2}{2.T_0.U_0}.k'}}{-\frac{\beta^2}{2.T_0.U_0}}.k_c \\
&= -\frac{2.T_0.U_0}{\beta^2} \cdot \sqrt{\frac{\beta^2.k'}{2.T_0.U_0}}.k_c
\end{aligned}$$

For all cases, by default we assume (if not precised as a limit),

$$\begin{aligned}
\beta &= 0 \\
U_0 &= 1 \\
F_1^* &= \frac{1}{R_d^2} = 0 \\
\frac{\Theta_0}{U_0} &= 1 \\
K_c^2 &= -\frac{\beta^2}{4.T_0.U_0}
\end{aligned}$$

For $\beta \gg$ parameters

Considering $\beta \gg$ parameters is equivalent to make $\beta \rightarrow +\infty$ so,

$$\begin{aligned}
\lim_{\beta \rightarrow +\infty} \sigma_i &= \lim_{\beta \rightarrow +\infty} -\frac{2.T_0.U_0}{\beta^2} \cdot \sqrt{\frac{\beta^2.k'}{2.T_0.U_0}}.k_c \\
&= 0 \times \sqrt{\frac{\beta^2.k'}{2.T_0.U_0}}.k_c = 0
\end{aligned}$$

This result is coherent numerically.

3.2.8. Marginality : when we are very close to the Non-Linear bound

When $\Delta \propto -\sqrt{\varepsilon}$ we consider the critical conditions,

$$\begin{aligned}\beta &= \beta_{\mathbf{c}} - \varepsilon \\ F_{1\mathbf{c}}^* &= F_{1\mathbf{c}}^* - \varepsilon\end{aligned}$$

That we replace in our $\Delta = 0 = (\beta - T_0 + \bar{U}.F_{1\mathbf{c}}^*)^2 + 4.(k^2 + l^2 + F_{1\mathbf{c}}^*).M^2.\bar{U}$ when we are in critical conditions, for simplicity for the moment we set $A = F_{1\mathbf{c}}^* - \varepsilon$

$$\begin{aligned}0 &= (\beta_{\mathbf{c}} - \varepsilon - T_0 + \bar{U}.A)^2 + 4.(k^2 + l^2 + A).M^2.\bar{U} \\ 0 &= \beta_{\mathbf{c}}^2 - 2.\beta_{\mathbf{c}}.\varepsilon - 2.\beta_{\mathbf{c}}.T_0 + 2.\beta_{\mathbf{c}}.A - 2.A.\varepsilon + 2.\varepsilon.T_0 + T_0^2 + A^2 - 2.A.T_0 \\ &\quad + 4.(k^2 + l^2 + A).M^2.\bar{U} \\ 0 &= \beta_{\mathbf{c}}^2 - 2.\beta_{\mathbf{c}}.\varepsilon - 2.\beta_{\mathbf{c}}.T_0 + 2.\beta_{\mathbf{c}}.(F_{1\mathbf{c}}^* - \varepsilon) - 2.(F_{1\mathbf{c}}^* - \varepsilon).\varepsilon + 2.\varepsilon.T_0 + T_0^2 \\ &\quad + (F_{1\mathbf{c}}^* - \varepsilon)^2 - 2.(F_{1\mathbf{c}}^* - \varepsilon).T_0 + 4.(k^2 + l^2 + F_{1\mathbf{c}}^* - \varepsilon).M^2.\bar{U} \\ 0 &= \beta_{\mathbf{c}}^2 - 2.\beta_{\mathbf{c}}.\varepsilon - 2.\beta_{\mathbf{c}}.T_0 + 2.\beta_{\mathbf{c}}.F_{1\mathbf{c}}^* - 2.\beta_{\mathbf{c}}.\varepsilon - 2.\varepsilon.F_{1\mathbf{c}}^* + 2.\varepsilon^2 + 2.\varepsilon.T_0 + T_0^2 \\ &\quad + (F_{1\mathbf{c}}^*)^2 - 2.F_{1\mathbf{c}}^*.\varepsilon + \varepsilon^2 - 2.T_0.F_{1\mathbf{c}}^* + 2.T_0.\varepsilon + 4.(k^2 + l^2).M^2.\bar{U} + 4.M^2.\bar{U}.F_{1\mathbf{c}}^* - 4.M^2.\bar{U}.\varepsilon\end{aligned}$$

At ε^2 we get,

$$2 + 1 = 3$$

At ε we get,

$$\begin{aligned}&= -2.\beta_{\mathbf{c}} - 2.\beta_{\mathbf{c}} - 2.F_{1\mathbf{c}}^* + 2.T_0 - 2.F_{1\mathbf{c}}^* + 2.T_0 - 4.M^2.\bar{U} \\ &= -4.\beta_{\mathbf{c}} - 4.F_{1\mathbf{c}}^* + 4.T_0 - 4.M^2.\bar{U}\end{aligned}$$

At ε^0 we get,

$$\begin{aligned}&= \beta_{\mathbf{c}}^2 - 2.\beta_{\mathbf{c}}.T_0 + 2.\beta_{\mathbf{c}}.F_{1\mathbf{c}}^* + T_0^2 + (F_{1\mathbf{c}}^*)^2 - 2.T_0.F_{1\mathbf{c}}^* + 4.(k^2 + l^2).M^2.\bar{U} + 4.M^2.\bar{U}.F_{1\mathbf{c}}^* \\ &= \beta_{\mathbf{c}}.(\beta_{\mathbf{c}} - 2.T_0 + 2.F_{1\mathbf{c}}^*) + T_0.(T_0 - 2.F_{1\mathbf{c}}^*) + F_{1\mathbf{c}}^*. (F_{1\mathbf{c}}^* + 4.M^2.\bar{U}) + 4.(k^2 + l^2).M^2.\bar{U}\end{aligned}$$

For $\beta_{\mathbf{c}}$ and $F_{1\mathbf{c}}^* = 0$

At ε^2 there's no expression.

At ε^1 (assume C_1 a constant),

$$\begin{aligned}C_1 &= -4.\beta_{\mathbf{c}} - \cancel{4.F_{1\mathbf{c}}^*}^0 + 4.T_0 - 4.M^2.\bar{U} \\ \frac{C_1 - 4.T_0 - 4.M^2.\bar{U}}{-4} &= \beta_{\mathbf{c}}\end{aligned}$$

At ε^0 (assume C_2 and Z_2 as constants),

$$\begin{aligned}C_2 &= \beta_{\mathbf{c}}.(\beta_{\mathbf{c}} - 2.T_0 + \cancel{2.F_{1\mathbf{c}}^*})^0 + T_0.(T_0 - \cancel{2.F_{1\mathbf{c}}^*})^0 + \cancel{F_{1\mathbf{c}}^*. (F_{1\mathbf{c}}^* + 4.M^2.\bar{U})}^0 + 4.(k^2 + l^2).M^2.\bar{U} \\ C_2 &= \beta_{\mathbf{c}}^2 - 2.T_0.\beta_{\mathbf{c}} + T_0^2 + 4.(k^2 + l^2).M^2.\bar{U} \\ 0 &= \beta_{\mathbf{c}}^2 - 2.T_0.\beta_{\mathbf{c}} + \underbrace{T_0^2 + 4.(k^2 + l^2).M^2.\bar{U}}_{Z_2} - C_2\end{aligned}$$

That is a polynomial equation, with discriminant $\delta = b^2 - 4.a.c = 4.T_0^2 - 4.Z_2 = 4.(T_0^2 - Z_2)$. To be instable we assume $\delta < 0$ and so the roots are,

$$\begin{aligned} r_i^\pm &= \frac{2.T_0}{2} \pm \frac{i.\sqrt{-4.(T_0^2 - Z_2)}}{2} \\ &= T_0 \pm i.\sqrt{-(T_0^2 - Z_2)} \end{aligned}$$

To be critical we can assume $\delta = 0$ so the roots are,

$$r_c = T_0$$

For $\bar{U} - c$ we have (consider $l = \beta = 0$)

And for $\delta > 0$ we have,

$$r_r^\pm = T_0 \pm \sqrt{T_0^2 - Z_2}$$

For $\beta_c = 0$ and F_{1c}^*

At ε^2 there's no expression.

At ε^1 (assume N_1 a constant),

$$\begin{aligned} N_1 &= \cancel{4.\beta_c} \overset{0}{- 4.F_{1c}^*} + 4.T_0 - 4.M^2.\bar{U} \\ -\frac{N_1 - 4.T_0 + 4.M^2.\bar{U}}{4} &= F_{1c}^* \end{aligned}$$

At ε^0 (assume N_2 and Q_2 as constants),

$$\begin{aligned} N_2 &= \beta_c.(\beta_c - 2.T_0 + 2.F_{1c}^*) + T_0.(T_0 - 2.F_{1c}^*) + F_{1c}^*. (F_{1c}^* + 4.M^2.\bar{U}) + 4.(k^2 + l^2).M^2.\bar{U} \\ &= \cancel{T_0^2} - 2.T_0.F_{1c}^* + F_{1c}^{*2} + 4.F_{1c}^*.M^2.\bar{U} + 4.(k^2 + l^2).M^2.\bar{U} \\ &= F_{1c}^{*2} + F_{1c}^*.(-2.T_0 + 4.M^2.\bar{U}) + \underbrace{4.(k^2 + l^2).M^2.\bar{U} + T_0^2}_{Q_2} \end{aligned}$$

That is a polynomial equation, with discriminant $\delta = b^2 - 4.a.c = (-2.T_0 + 4.M^2.\bar{U})^2 - 4.Q_2$. To be instable we assume $\delta < 0$ and so the roots are,

$$r_i^\pm = -\frac{-2.T_0 + 4.M^2.\bar{U}}{2} \pm \frac{i.\sqrt{-(-2.T_0 + 4.M^2.\bar{U})^2 - 4.Q_2}}{2}$$

To be critical we can assume $\delta = 0$ so the roots are,

$$r_c = \frac{2.T_0 - 4.M^2.\bar{U}}{2}$$

And for $\delta > 0$ we have,

$$r_r^\pm = -\frac{-2.T_0 + 4.M^2.\bar{U}}{2} \pm \frac{\sqrt{(-2.T_0 + 4.M^2.\bar{U})^2 - 4.Q_2}}{2}$$

3.2.9. Growth rate (II)

To find growth rates of c (that is a scalar) given by (8), we need to look for,

$$\sigma_i = k \cdot \text{Im}\{c\} \quad (12)$$

Where k is the wavenumber, and c eigenvalues. The growth rate gives us an indication of the energy of the little perturbations. When growth rates increase, the energy is distributed into small perturbations. We show in **Fig. 1**. an example of 2 growth rates : QG and TQG. computed with the numerical model presented from **page 20**.

To simplify the analysis, we will explore the stability of the system with growth rates numerically.

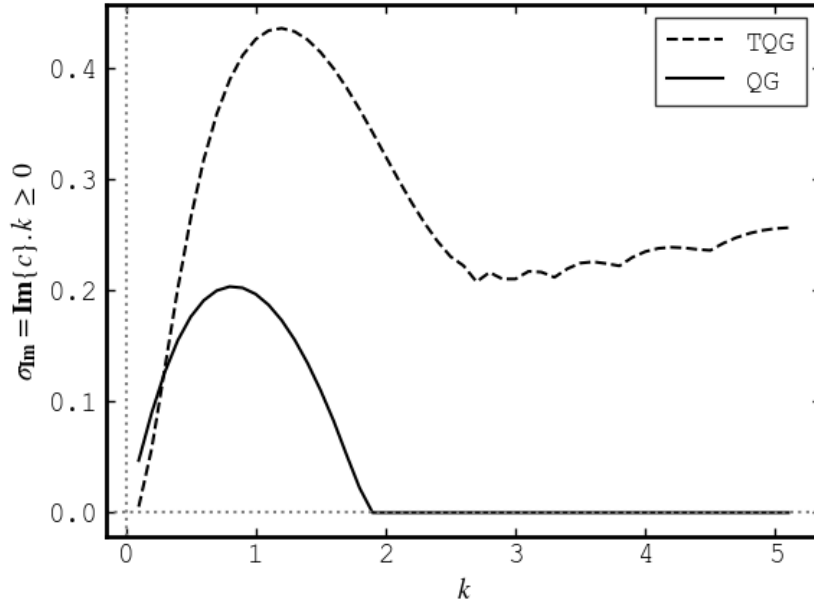


Fig. 1. A random example of growth rates between QG and TQG models. We see the difference of amplitude and shape. We see that the QG is very smooth along wavenumber k and it becomes null when $k \rightarrow 2$. The TQG one is not that smooth after $k = 2.75$ and becomes bouncy : that is typically observed when we use thermal forcing.

We know,

$$\sigma_i = -\frac{2.T_0.U_0}{\beta^2} \cdot \sqrt{\frac{\beta^2.k'}{2.T_0.U_0}} \cdot k_c$$

We can compute the derivative of this function with respect to β . We know $u = \frac{2.T_0.U_0}{\beta^2}$ and $v = \sqrt{\frac{\beta^2.k'}{2.T_0.U_0}} \cdot k_{\text{critical}}$ so we deduce : $u' = -\frac{2.T_0.U_0}{\beta^3}$ and $v' = \frac{2.k' \cdot \beta}{2.T_0.U_0} \cdot \frac{k_c}{2 \cdot \sqrt{\frac{\beta^2.k'}{2.T_0.U_0}}}$

$$\begin{aligned}
\frac{\partial \sigma_i}{\partial \beta} &= -\frac{\partial}{\partial \beta} \frac{2.T_0.U_0}{\beta^2} \cdot \sqrt{\frac{\beta^2.k'}{2.T_0.U_0}} . k_{\text{critical}} \\
&= -\frac{2.T_0.U_0}{\beta^3} \cdot \sqrt{\frac{\beta^2.k'}{2.T_0.U_0}} . k_{\text{critical}} + \frac{2.T_0.U_0}{\beta^2} \cdot \frac{2.k'.\beta}{2.T_0.U_0} \cdot \frac{k_{\text{critical}}}{2.\sqrt{\frac{\beta^2.k'}{2.T_0.U_0}}} \\
&= -\frac{2.T_0.U_0}{\beta^3} \cdot \sqrt{\frac{\beta^2.k'}{2.T_0.U_0}} . k_{\text{critical}} + \frac{2.k'.k_{\text{critical}}}{2.\beta.\sqrt{\frac{\beta^2.k'}{2.T_0.U_0}}}
\end{aligned}$$

For the F_1^* we can proceed similarly but we recall the other form of σ_i , that is

$$\sigma_i = \frac{\sqrt{-\Delta}}{2.K^2} . k$$

Ans as long we know $d\sqrt{u(x)} = \frac{du}{2.\sqrt{u}}$ we deduce that,

$$\frac{d\sigma_i}{dF_1^*} = -\frac{d\Delta}{dF_1^*} \cdot \frac{1}{4.K_\gamma^2.\sqrt{-\Delta}}$$

Normally the second term has a frozen sign and this is the first one that should be modified and informs us on the stability. We consider that the solutions are stable if $\Delta > 0$ and unstable if $\Delta < 0$. We recall that $F_1^* = \frac{1}{R_d^2}$ and knowing $\Delta = (\beta - T_0 + \bar{U}.F_1^*)^2 + 4.K_\gamma^2.M^2.\bar{U}$ and $K_\gamma^2 = k^2 + l^2 + F_1^*$

$$\begin{aligned}
\frac{d\Delta}{dF_1^*} &= \frac{d}{dF_1^*} \cdot \left((\beta - T_0 + \bar{U}.F_1^*)^2 + 4.(k^2 + l^2 + F_1^*).M^2.\bar{U} \right) \\
&= \beta.U - T_0.U + U.\beta - U.T_0 + 2.U^2.F_1^* + 4.M^2.U \\
&= 2.U.\beta - 2.U.T_0 + 4.M^2.U + 2.U^2.F_1^* \\
&= U.(2.\beta - 2.T_0 + 4.M^2 + 2.U.F_1^*)
\end{aligned}$$

So the complete expression is,

$$\frac{d\sigma_i}{dF_1^*} = -\frac{U.(2.\beta - 2.T_0 + 4.M^2 + 2.U.F_1^*)}{4.(k^2 + l^2 + F_1^*).\sqrt{-((\beta - T_0 + \bar{U}.F_1^*)^2 + 4.(k^2 + l^2 + F_1^*).M^2.\bar{U})}}$$

3.3. The system for $\bar{\psi} = f(y)$ and $\bar{\Theta} = M^2.y$

Instead of considering $\bar{\psi} = -\bar{U}.y$ we will assume that it's a function depending on $y : \bar{\psi} = f(y)$. Some details of the previous equations will change ...

3.3.1. Linearisation & wave hypothesis

The linearisation presented in **page 6** at section 3.2.1 is valid for this case. We have the same set of equation that are (4a) and (4b) that are,

$$\begin{aligned}
\frac{\partial q'}{\partial t} + J(\bar{\psi}, q' - \Theta') + J(\psi', \bar{q} - \bar{\Theta}) &= 0 \\
\frac{\partial \Theta'}{\partial t} + J(\bar{\psi}, \Theta') + J(\psi', \bar{\Theta}) &= 0
\end{aligned}$$

As usual we consider that $\bar{\Theta} = M^2.y$, $\bar{q} = \left(\frac{\bar{U}}{R_d^2} + \beta \right).y$ and now $\bar{\psi} = f(y)$,

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Step 1 : $q - \Theta$

$$\begin{aligned} \frac{\partial q'}{\partial t} + \cancel{\partial_x \bar{\psi} \cdot \partial_y (q' - \Theta')}^0 - \partial_x (q' - \Theta') \cdot \partial_y \bar{\psi} + \partial_x \psi' \cdot \partial_y (\bar{q} - \bar{\Theta}) - \cancel{\partial_x (\bar{q} - \bar{\Theta}) \cdot \partial_y \psi'}^0 &= 0 \\ \frac{\partial q'}{\partial t} - \partial_x (q' - \Theta') \cdot \partial_y \bar{\psi} + \partial_x \psi' \cdot \partial_y (\bar{q} - \bar{\Theta}) &= 0 \end{aligned}$$

And replacing the known terms into the equation we get (we don't forget that $q' = \text{div}(\underline{\text{grad}} \psi') - \frac{\psi'}{R_d^2} + \beta \cdot y$),

$$\begin{aligned} \frac{\partial}{\partial t} \cdot \left(\text{div}(\underline{\text{grad}} \psi') - \frac{\psi'}{R_d^2} + \beta \cdot y \right) - \partial_x \left(\text{div}(\underline{\text{grad}} \psi') - \frac{\psi'}{R_d^2} + \beta \cdot y - \Theta' \right) \cdot \partial_y f(y) \\ + \partial_x \psi' \cdot \partial_y \cdot \left(\left(\frac{\bar{U}}{R_d^2} + \beta \right) \cdot y - M^2 \cdot y \right) &= 0 \\ \frac{\partial}{\partial t} \cdot \left(\text{div}(\underline{\text{grad}} \psi') - \frac{\psi'}{R_d^2} \right) - \partial_x \left(\text{div}(\underline{\text{grad}} \psi') - \frac{\psi'}{R_d^2} - \Theta' \right) \cdot \frac{df(y)}{dy} \\ + \partial_x \psi' \cdot \left(\frac{\bar{U}}{R_d^2} + \beta - M^2 \right) &= 0 \end{aligned}$$

As usual, we use the wave-hypothesis : $\psi' = \hat{\psi}' \cdot \exp(i \cdot (k \cdot x + l \cdot y - \omega \cdot t)) = \hat{\psi}' \cdot \exp(\aleph)$ and the same for Θ' (as usual we remove the $\exp(\aleph)$ by dividing for lisibility ...),

$$\begin{aligned} -i \cdot \omega \cdot \left(-\left(k^2 + l^2 + \frac{1}{R_d^2}\right) \cdot \hat{\psi}' \right) - i \cdot k \cdot \left(-\left(k^2 + l^2 + \frac{1}{R_d^2}\right) \cdot \hat{\psi}' - \Theta' \right) \cdot \frac{df(y)}{dy} \\ + i \cdot k \cdot \psi' \cdot \left(\frac{\bar{U}}{R_d^2} + \beta - M^2 \right) = 0 \quad || \times \frac{1}{i \cdot k} \\ -c \cdot \left(-\left(k^2 + l^2 + \frac{1}{R_d^2}\right) \cdot \hat{\psi}' \right) - \left(-\left(k^2 + l^2 + \frac{1}{R_d^2}\right) \cdot \hat{\psi}' - \Theta' \right) \cdot \frac{df(y)}{dy} \\ + \hat{\psi}' \cdot \left(\frac{\bar{U}}{R_d^2} + \beta - M^2 \right) = 0 \end{aligned}$$

We recall that $K_\gamma^2 = k^2 + l^2 + \frac{1}{R_d^2}$ and $\alpha = \beta - M^2 + \frac{\bar{U}}{R_d^2}$ and so,

$$\begin{aligned} -c \cdot \left(-K_\gamma^2 \cdot \hat{\psi}' \right) + \left(K_\gamma^2 \cdot \hat{\psi}' + \Theta' \right) \cdot \frac{df(y)}{dy} + \psi' \cdot \alpha &= 0 \\ \left(\left(c + \frac{df(y)}{dy} \right) \cdot K_\gamma^2 + \alpha \right) \cdot \hat{\psi}' + \frac{df(y)}{dy} \cdot \hat{\Theta}' &= 0 \end{aligned}$$

Step 2 : Θ

$$\begin{aligned} \frac{\partial \Theta'}{\partial t} + \cancel{\partial_x \bar{\psi} \cdot \partial_y \Theta'}^0 - \partial_x \Theta' \cdot \partial_y \bar{\psi} + \partial_x \psi' \cdot \partial_y \bar{\Theta} - \cancel{\partial_x \bar{\Theta} \cdot \partial_y \psi'}^0 &= 0 \\ \frac{\partial \Theta'}{\partial t} - \partial_x \Theta' \cdot \partial_y \bar{\psi} + \partial_x \psi' \cdot \partial_y \bar{\Theta} &= 0 \end{aligned}$$

Now we replace with known values that are $\Theta = M^2 \cdot y$ and $\bar{\psi} = f(y)$,

$$\begin{aligned} \frac{\partial \Theta'}{\partial t} - \partial_x \Theta' \cdot \partial_y f(y) + \partial_x \psi' \cdot \partial_y M^2 \cdot y &= 0 \\ \frac{\partial \Theta'}{\partial t} - \partial_x \Theta' \cdot \frac{df(y)}{dy} + \partial_x \psi' \cdot M^2 &= 0 \end{aligned}$$

And now we set the wave hypothesis $\psi' = \hat{\psi}' \cdot \exp(\aleph)$ for ψ' and Θ' ,

$$\begin{aligned} \frac{\partial \Theta'}{\partial t} - \partial_x \Theta' \cdot \frac{df(y)}{dy} + \partial_x \psi' \cdot M^2 &= 0 \\ -i \cdot \omega \cdot \hat{\Theta}' \cdot \exp(\aleph) - i \cdot k \cdot \hat{\Theta}' \cdot \exp(\aleph) \cdot \frac{df(y)}{dy} + i \cdot k \cdot \hat{\psi}' \cdot \exp(\aleph) \cdot M^2 &= 0 \quad || \times \frac{1}{i \cdot k \cdot \exp(\aleph)} \\ \left(\frac{df(y)}{dy} - c \right) \cdot \hat{\Theta}' + \hat{\psi}' \cdot M^2 &= 0 \end{aligned}$$

We have a new set of equations (13a) and (13b) for the case where $\psi' = f(y)$,

$$\boxed{\left(\left(c + \frac{df(y)}{dy} \right) \cdot K_\gamma^2 + \alpha \right) \cdot \hat{\psi}' + \frac{df(y)}{dy} \cdot \hat{\Theta}' = 0} \quad (13a)$$

$$\boxed{\left(\frac{df(y)}{dy} - c \right) \cdot \hat{\Theta}' + \hat{\psi}' \cdot M^2 = 0} \quad (13b)$$

3.3.2. Solving for $\Theta' = 0$

From (13a) and (13b) and considering $\Theta' = 0$: the set of equation, for $\Theta' = 0$ is,

$$\begin{aligned} \left(\left(c + \frac{df(y)}{dy} \right) \cdot K_\gamma^2 + \alpha \right) \cdot \hat{\psi}' &= 0 \\ \hat{\psi}' \cdot M^2 &= 0 \end{aligned}$$

From the second equation we deduce that $M^2 = 0$ because $\hat{\psi}'$ can't be 0 (unless if we are looking for 0-solutions). We separate the c value that gives a simple equation to solve,

$$\left(c + \frac{df(y)}{dy} \right) \cdot K_\gamma^2 + \alpha = 0$$

And so,

$$\boxed{c = -\frac{\alpha}{K_\gamma^2} - \frac{df(y)}{dy}} \quad (14)$$

3.3.3. Solving for $\Theta' \neq 0$

From (13a) and (13b) :

$$\begin{aligned} \left(\left(c + \frac{df(y)}{dy} \right) \cdot K_\gamma^2 + \alpha \right) \cdot \hat{\psi}' + \frac{df(y)}{dy} \cdot \hat{\Theta}' &= 0 \\ \left(\frac{df(y)}{dy} - c \right) \cdot \hat{\Theta}' + \hat{\psi}' \cdot M^2 &= 0 \end{aligned}$$

If $\Theta' \neq 0$ we see a matrix system $A \times v = 0$ that can be written as,

$$\underbrace{\begin{pmatrix} \left(c + \frac{df(y)}{dy} \right) \cdot K_\gamma^2 + \alpha & \frac{df(y)}{dy} \\ M^2 & \frac{df(y)}{dy} - c \end{pmatrix}}_{\underline{A}} \times \underbrace{\begin{pmatrix} \hat{\psi}' \\ \hat{\Theta}' \end{pmatrix}}_v = \begin{pmatrix} 0 \\ 0 \end{pmatrix}$$

As usual we can try a null determinant method to solve this system, that gives,

$$\begin{aligned}
& \det \underline{A} = 0 \\
& \left[\left(c + \frac{df(y)}{dy} \right) \cdot K_\gamma^2 + \alpha \right] \cdot \left(\frac{df(y)}{dy} - c \right) - M^2 \cdot \frac{df(y)}{dy} = 0 \\
& \left(c + \frac{df(y)}{dy} \right) \cdot K_\gamma^2 \cdot \frac{df(y)}{dy} + \alpha \cdot \frac{df(y)}{dy} - \left(c + \frac{df(y)}{dy} \right) \cdot K_\gamma^2 \cdot c - c \cdot \alpha - M^2 \cdot \frac{df(y)}{dy} = 0 \\
& \cancel{c \cdot K_\gamma^2 \cdot \frac{df(y)}{dy}} + K_\gamma^2 \left(\frac{df(y)}{dy} \right)^2 + \alpha \cdot \frac{df(y)}{dy} - \cancel{K_\gamma^2 \cdot c^2} - \cancel{\frac{df(y)}{dy} \cdot K_\gamma^2 \cdot c} - c \cdot \alpha - M^2 \cdot \frac{df(y)}{dy} = 0 \\
& \underbrace{-c^2 \cdot K_\gamma - c \cdot \alpha + \frac{df(y)}{dy} \cdot (\alpha - M^2) + \left(\frac{df(y)}{dy} \right)^2 \cdot K_\gamma^2}_\eta = 0 \quad \Bigg\| \times (-1)
\end{aligned}$$

That's a 2nd order polynomial equation,

$$c^2 + c \cdot \alpha - \eta = 0$$

With $k_1 = 1$; $k_2 = \alpha = \beta - M^2 + \frac{\bar{U}}{R_d^2}$; $k_3 = \eta$ and c will depends of the sign of the discriminant $\Delta = k_2^2 - 4 \cdot k_1 \cdot k_3$,

$$\begin{aligned}
\Delta &= \alpha^2 - 4 \times 1 \times \eta \\
&= \alpha^2 - 4 \cdot \eta
\end{aligned}$$

3.3.4. Stability criteria

We need an imaginary part, so to have complex solutions, we must have $\Delta < 0$. If $\alpha^2 > 0$ that implies,

$$\alpha^2 - 4 \cdot \eta < 0$$

$$\boxed{\eta > \frac{1}{4} \cdot \alpha^2 \text{ with } \alpha = \beta - M^2 + \frac{\bar{U}}{R_d^2}} \quad (15)$$

The conditions where we can solve for $\Theta' \neq 0$ is $\eta > \frac{1}{4} \cdot \alpha^2$. And this equation is a stability criteria for $\eta = \frac{df(y)}{dy} \cdot (\alpha - M^2) + \left(\frac{df(y)}{dy} \right)^2 \cdot K_\gamma^2$

3.4. General equations for the numerical part

3.4.1. Set the system

We will derive a stability criteria for the following system derived from (4a) and (4b) that are,

$$\begin{aligned}
\frac{\partial q'}{\partial t} + J(\psi', \bar{q} - \bar{\Theta}) + J(\bar{\psi}, q' - \Theta') &= 0 \\
\frac{\partial \Theta'}{\partial t} + J(\bar{\psi}, \Theta') + J(\psi', \bar{\Theta}) &= 0
\end{aligned}$$

We recall the following parameters $\bar{\psi} = -\bar{U} \cdot y$; $\bar{q} = \left(\frac{\bar{U}}{R_d^2} + \beta \right) \cdot y$; $\bar{\Theta} = f(y)$. And we recall that for any pertubations $\lambda' = \hat{\lambda} \cdot \exp(\aleph)$, always with $\aleph = i \cdot (k \cdot x + l \cdot y - \omega \cdot t)$.

Step 1 : $q - \Theta$,

$$\begin{aligned} \frac{\partial q'}{\partial t} + \partial_x \psi' \cdot \partial_y (\bar{q} - \bar{\Theta}) - \cancel{\partial_x (\bar{q} - \bar{\Theta}) \cdot \partial_y \psi'} + \cancel{\partial_x \bar{\psi} \cdot \partial_y (q' - \Theta')} - \partial_x (q' - \Theta') \cdot \partial_y \bar{\psi} &= 0 \\ \frac{\partial q'}{\partial t} + \partial_x \psi' \cdot \frac{d}{dy} (\bar{q} - \bar{\Theta}) + \partial_x (q' - \Theta') \cdot \bar{U} &= 0 \\ -i \cdot \omega \cdot \hat{q}' \cdot \mathbf{exp}(\mathbb{N}) + i \cdot k \cdot \hat{\psi}' \cdot \mathbf{exp}(\mathbb{N}) \cdot \frac{d}{dy} (\bar{q} - \bar{\Theta}) + i \cdot k \cdot \mathbf{exp}(\mathbb{N}) \cdot (\hat{q}' - \hat{\Theta}') \cdot \bar{U} &= 0 \end{aligned}$$

As usual, we multiply by $\times \frac{1}{i \cdot k \cdot \mathbf{exp}(\mathbb{N})}$ that gives (and we recall that $c = \frac{\omega}{k}$),

$$\begin{aligned} -c \cdot \hat{q}' + \hat{\psi}' \cdot \frac{d}{dy} (\bar{q} - \bar{\Theta}) + (\hat{q}' - \hat{\Theta}') \cdot \bar{U} &= 0 \\ (\bar{U} - c) \cdot \hat{q}' - \bar{U} \cdot \hat{\Theta}' + \hat{\psi}' \cdot \frac{d}{dy} (\bar{q} - \bar{\Theta}) &= 0 \end{aligned}$$

Step 2 : Θ

$$\begin{aligned} \frac{\partial \Theta'}{\partial t} + \partial_x \psi' \cdot \partial_y \bar{\Theta} - \cancel{\partial_x \bar{\Theta} \cdot \partial_y \psi'} + \cancel{\partial_x \bar{\psi} \cdot \partial_y \Theta'} - \partial_x \Theta' \cdot \partial_y \bar{\psi} &= 0 \\ \frac{\partial \Theta'}{\partial t} + \partial_x \psi' \cdot \partial_y \bar{\Theta} - \partial_x \Theta' \cdot \partial_y \bar{\psi} &= 0 \\ -i \cdot \omega \cdot \hat{\Theta}' \cdot \mathbf{exp}(\mathbb{N}) + i \cdot k \cdot \hat{\psi}' \cdot \mathbf{exp}(\mathbb{N}) \cdot \frac{d\bar{\Theta}}{dy} + i \cdot k \cdot \hat{\Theta}' \cdot \mathbf{exp}(\mathbb{N}) \cdot \bar{U} &= 0 \end{aligned}$$

We multiply by $\times \frac{1}{i \cdot k \cdot \mathbf{exp}(\mathbb{N})}$,

$$\begin{aligned} -c \cdot \hat{\Theta}' + \hat{\psi}' \cdot \frac{d\bar{\Theta}}{dy} + \hat{\Theta}' \cdot \bar{U} &= 0 \\ (\bar{U} - c) \cdot \hat{\Theta}' + \hat{\psi}' \cdot \frac{d\bar{\Theta}}{dy} &= 0 \end{aligned}$$

The 2 equations that we need to study are,

$$\boxed{(\bar{U} - c) \cdot \hat{q}' - \bar{U} \cdot \hat{\Theta}' + \hat{\psi}' \cdot \frac{d}{dy} (\bar{q} - \bar{\Theta}) = 0} \quad (16a)$$

$$\boxed{(\bar{U} - c) \cdot \hat{\Theta}' + \hat{\psi}' \cdot \frac{d\bar{\Theta}}{dy} = 0} \quad (16b)$$

3.5. Non-Linearity

So we re-start from the original equations (with the PV : $q = \beta \cdot y + \mathbf{div}(\mathbf{grad} \psi) - \frac{\psi}{R_d^2}$) that are

$$\begin{aligned} \frac{\partial q}{\partial t} + J(\psi, q - \Theta) &= 0 \\ \frac{\partial \Theta}{\partial t} + J(\psi, \Theta) &= 0 \end{aligned}$$

The non-linearity appears when we write a λ quantity such that $\lambda = \bar{\lambda} + \lambda'$

$$\begin{aligned}\frac{\partial(\bar{q} + q')}{\partial t} + J(\bar{\psi}, \bar{q} - \bar{\Theta}) + J(\bar{\psi}, q' - \Theta') + J(\psi', \bar{q} - \bar{\Theta}) + J(\psi', q' - \Theta') &= 0 \\ \frac{\partial(\bar{\Theta} + \Theta')}{\partial t} + J(\bar{\psi}, \bar{\Theta}) + J(\bar{\psi}, \Theta') + J(\psi', \bar{\Theta}) + J(\psi', \Theta') &= 0\end{aligned}$$

This part can be solved thanks to the spectral code `ttgg256.f`. [A DETAILLER SI BESOIN]

4. Numerical investigation of the TQG model

4.1. TQG Numerical solution

We are now able to propose a method to solve numerically the equations (16a) and (16b). As references the Rouillet's courses provides elements of numerical methods with [Rouillet, 2023a] and [Rouillet, 2023b].

4.1.1. Before the numerical analysis



We set

Now we will set that (with $\aleph = i.(k.x + l.y - \omega.t)$),

$$\begin{aligned}q' &= \left(\frac{d^2\phi}{dy^2} - k_d^2 \cdot \phi \right) \cdot \exp(\aleph) ; \quad k_d^2 = k^2 + \frac{1}{R_d^2} ; \quad K^2 = k_d^2 \cdot \Delta_y^2 \\ \frac{d\bar{q}}{dy} &= -\frac{d^2\bar{U}}{dy^2} + \frac{\bar{U}}{R_d^2} + \beta ; \quad G_{11} = \frac{d}{dy}(\bar{q} - \bar{\Theta}) ; \quad G_{12} = \frac{d\bar{\Theta}}{dy}\end{aligned}$$

We assume that $\psi' = \phi \cdot \exp(\aleph)$ and $\Theta' = \hat{\Theta}' \cdot \exp(\aleph)$ so from (16a) we get

$$\begin{aligned}(\bar{U} - c) \cdot \tilde{q}' - \bar{U} \cdot \hat{\Theta}' + \hat{\psi}' \cdot \frac{d}{dy}(\bar{q} - \bar{\Theta}) &= 0 \\ (\bar{U} - c) \cdot \left(\frac{d^2}{dy^2} - k_d^2 \right) \cdot \phi \cdot \exp(\aleph) - \bar{U} \cdot \hat{\Theta}' \cdot \exp(\aleph) + \phi \cdot \exp(\aleph) \cdot G_{11} &= 0 \quad || \times \frac{1}{\exp(\aleph)} \\ (\bar{U} - c) \cdot \left(\frac{d^2\phi}{dy^2} - \phi \cdot k_d^2 \right) - \bar{U} \cdot \hat{\Theta}' + \phi \cdot G_{11} &= 0\end{aligned}$$

From (16b) we get,

$$\begin{aligned}(\bar{U} - c) \cdot \hat{\Theta}' + \hat{\psi}' \cdot \frac{d\bar{\Theta}}{dy} &= 0 \\ (\bar{U} - c) \cdot \hat{\Theta}' \cdot \exp(\aleph) + \phi \cdot \exp(\aleph) \cdot \frac{d\bar{\Theta}}{dy} &= 0 \quad || \times \frac{1}{\exp(\aleph)} \\ (\bar{U} - c) \cdot \hat{\Theta}' + \phi \cdot G_{12} &= 0\end{aligned}$$

We get,

$$\boxed{(\bar{U} - c) \cdot \left(\frac{d^2\phi}{dy^2} - \phi \cdot k_d^2 \right) - \bar{U} \cdot \hat{\Theta}' + \phi \cdot G_{11} = 0} \tag{17a}$$

$$\boxed{(\bar{U} - c) \cdot \hat{\Theta}' + \phi \cdot G_{12} = 0} \tag{17b}$$

4.1.2. The analytical principle of an eigenvalue problem

We shall now introduce the following system that will drives the numerical solution of the TQG model,

$$\begin{aligned}\underline{\underline{A}}.X &= c.\underline{\underline{B}}.X \\ \underbrace{\underline{\underline{B}}^{-1}.\underline{\underline{A}}}_{\underline{\underline{P}}}.X &= \underline{\underline{c}}.X \\ \underline{\underline{P}}.X &= \underline{\underline{c}}.X\end{aligned}$$

And $\underline{\underline{P}} = \underline{\underline{N}}.\underline{\underline{A}}.\underline{\underline{N}}^{-1}$, we note **Id** the identity matrix so,

$$\begin{aligned}\underline{\underline{P}}.X &= \underline{\underline{c}}.X \\ (\underline{\underline{P}} - \underline{\underline{c}}).\text{Id}.X &= 0\end{aligned}$$

We get the following system,

$$\det(\underline{\underline{P}} - \underline{\underline{c}}.\text{Id}) = 0$$

That gives eigenvalues in an eigenvector after a few lines of algebra.

4.1.3. Discretisation

Using finite differences we can transform the 2 equations presented in (17a) and (17b),

$$\begin{aligned}(\bar{U}_n - c) \cdot \left[\frac{\phi_{j+1} - 2\phi_n + \phi_{j-1}}{\Delta y^2} - \phi_n \cdot k_d^2 \right] - \bar{U}_n \cdot \Theta_n + \phi_n \cdot G_{11n} &= 0 \\ (\bar{U}_n - c) \cdot \Theta_n + \phi_n \cdot G_{12n} &= 0\end{aligned}$$



We set

Some usefull definitions,

$$K^2 = k_d^2 \cdot \Delta y^2 = \left(k^2 + \underbrace{\frac{1}{R_d^2}}_{F_1^*} \right) \cdot \Delta y^2 \quad \text{Be aware ! Not the same than } K_\gamma^2$$

$$F_{11n} = \Delta y^2 \cdot G_{11n}$$

$$F_1^* = \frac{1}{R_d^2}$$

$$\bar{V}_n = \bar{U}_n \cdot \Delta y^2$$

We can re-write the previous equation by multiplying it by Δy^2 .

For (17a) we get,

$$\begin{aligned}(\bar{U}_n - c) \cdot \left[\frac{\phi_{j+1} - 2\phi_n + \phi_{j-1}}{\Delta y^2} - \phi_n \cdot k_d^2 \right] - \bar{U}_n \cdot \Theta_n + \phi_n \cdot G_{11n} &= 0 \quad \left\| \times \Delta y^2 \right. \\ (\bar{U}_n - c) \cdot [\phi_{j+1} - 2\phi_n + \phi_{j-1} - \phi_n \cdot k_d^2 \cdot \Delta y^2] - \bar{U}_n \cdot \Theta_n \cdot \Delta y^2 + \phi_n \cdot G_{11n} \cdot \Delta y^2 &= 0 \\ (\bar{U}_n - c) \cdot [\phi_{j+1} - 2\phi_n + \phi_{j-1} - \phi_n \cdot K^2] - \bar{V}_n \cdot \Theta_n + \phi_n \cdot F_{11n} &= 0\end{aligned}$$

For (17b) we just have to set the indices n on the equation without modify it. We get the final system discretised with (18a) and (18b),

$$\boxed{(\bar{U}_n - c) \cdot [\phi_{j+1} - 2\phi_n + \phi_{j-1} - \phi_n \cdot K^2] - \bar{V}_n \cdot \Theta_n + \phi_n \cdot F_{1n} = 0} \quad (18a)$$

$$\boxed{(\bar{U}_n - c) \cdot \Theta_n + \phi_n \cdot G_{12n} = 0} \quad (18b)$$

That can be re-writed,

$$\begin{aligned} (\bar{U}_n - c) \cdot [\phi_{n+1} - 2\phi_n + \phi_{n-1} - \phi_n \cdot K^2] - \bar{V}_n \cdot \Theta_n + \phi_n \cdot F_{1n} &= 0 \\ (\bar{U}_n - c) \cdot \Theta_n + \phi_n \cdot G_{12n} &= 0 \end{aligned}$$

And,

$$\boxed{\bar{U}_n \cdot [\phi_{j+1} - 2\phi_n + \phi_{j-1} - \phi_n \cdot K^2] - \bar{V}_n \cdot \Theta_n + \phi_n \cdot F_{1n} = c \cdot [\phi_{j+1} - 2\phi_n + \phi_{j-1} - \phi_n \cdot K^2]} \quad (19a)$$

$$\boxed{\bar{U}_n \cdot \Theta_n + \phi_n \cdot G_{12n} = c \cdot \Theta_n} \quad (19b)$$

Now we set $X = \begin{pmatrix} \phi_n \\ \Theta_n \end{pmatrix}$ and we find a system defined by,

$$\boxed{\underline{\underline{A}} \cdot X = c \cdot \underline{\underline{B}} \cdot X} \quad (20)$$

4.1.4. Numerical proposition

And from (19a) and (19b) we detail the equation (20),

$$\underbrace{\begin{pmatrix} A_{11} & A_{12} \\ A_{21} & A_{22} \end{pmatrix}}_{\underline{\underline{A}}} \times \underbrace{\begin{pmatrix} \phi_n \\ \Theta_n \end{pmatrix}}_X = c \cdot \underbrace{\begin{pmatrix} B_{11} & B_{12} \\ B_{21} & B_{22} \end{pmatrix}}_{\underline{\underline{B}}} \times \underbrace{\begin{pmatrix} \phi_n \\ \Theta_n \end{pmatrix}}_X$$

And the associated matrix, for a 3×3 example are,

$$\begin{aligned} A_{11} &= \begin{pmatrix} -\bar{U}_n \cdot (2 + K^2) + F_{1n} & \bar{U}_n & 0 \\ \bar{U}_n & -\bar{U}_n \cdot (2 + K^2) + F_{1n} & \bar{U}_n \\ 0 & \bar{U}_n & -\bar{U}_n \cdot (2 + K^2) + F_{1n} \end{pmatrix} \\ A_{12} &= \begin{pmatrix} -\bar{V}_n & 0 & 0 \\ 0 & -\bar{V}_n & 0 \\ 0 & 0 & \bar{V}_n \end{pmatrix} \\ A_{21} &= \begin{pmatrix} G_{12n} & 0 & 0 \\ 0 & G_{12n} & 0 \\ 0 & 0 & G_{12n} \end{pmatrix} \rightarrow \text{that we substitute into } \underline{\underline{A}} = \begin{pmatrix} A_{11} & A_{12} \\ A_{21} & A_{22} \end{pmatrix} \\ A_{22} &= \begin{pmatrix} \bar{U}_n & 0 & 0 \\ 0 & \bar{U}_n & 0 \\ 0 & 0 & \bar{U}_n \end{pmatrix} \end{aligned}$$

With the same method we deduce the matrix B ,

$$\underline{\underline{B}} = \begin{pmatrix} B_{11} & B_{12} \\ B_{21} & B_{22} \end{pmatrix} = \begin{pmatrix} \overbrace{\begin{bmatrix} -(2+K^2) & 1 & 0 \\ 1 & -(2+K^2) & 1 \\ 0 & 1 & -(2+K^2) \end{bmatrix}}^{\text{Laplacian}} & \overbrace{\begin{bmatrix} 0 \\ 0 \\ 0 \end{bmatrix}}^{\underline{0}} \\ \underbrace{\begin{bmatrix} 0 & 0 & 0 \\ 0 & 0 & 0 \\ 0 & 0 & 0 \end{bmatrix}}_{\underline{0}} & \underbrace{\begin{bmatrix} 0 & 0 & 0 \\ 1 & 0 & 0 \\ 0 & 1 & 0 \\ 0 & 0 & 1 \end{bmatrix}}_{\text{Id}} \end{pmatrix}$$

We recall that,

$$\begin{aligned} \bar{V}_n &= \bar{U}_n \cdot \Delta y^2 \\ G_{12n} &= \frac{d\bar{\Theta}_n}{dy} = \frac{d}{dy} M_n^2 \cdot y \\ &= M_n^2 \\ G_{11n} &= \frac{d(\bar{q}_n - \bar{\Theta}_n)}{dy} = \frac{d}{dy} \left(\frac{\bar{U}_n}{R_d^2 + \beta} - M_n^2 \right) \cdot y = \\ &= \frac{\bar{U}_n}{R_d^2 + \beta} - M_n^2 \\ F_{1n} &= G_{11n} \cdot \Delta y^2 \\ K^2 &= k_d^2 \cdot \Delta y^2 = k^2 + \frac{1}{R_d^2} \end{aligned}$$

Note that the system $\underline{\underline{A}} \cdot X = \underline{\underline{c}} \cdot \underline{\underline{B}} \cdot X$ can be quickly solved with python modules : for instance `c, X = scipy.linalg.eig(A,B)` that returns eigenvalues and eigenvectors.

Warning : The system solved here gives us ϕ' and Θ' . If we want the complete value of ϕ or Θ we need to add the mean state of these 2 variables : $\bar{\phi}$ and $\bar{\Theta}$.

4.1.5. Tools

We want to study the stability of the system, and for that we can plot some charts that will helps us to interpret what we are simulating. We will first draw a chart that represents,

$$\sigma_{\text{Im}} = \text{Im}\{c\} \cdot k \quad (21a)$$

$$\sigma_{\text{Re}} = \text{Re}\{c\} \cdot k \quad (21b)$$

Where c are the eigenvalues computed with the numerical solving of $A \cdot \underline{X} = c \cdot B \cdot \underline{X}$, and k is the wavenumber. These parameters are called "growth rates".

If we want to visualise the $\phi(t, y)$ and $\Theta(t, y)$ values, we can use the following definitions. First we extract the mode that we want on the \underline{X} eigenvectors. Then we separate $\phi(y)$ and $\Theta(y)$ (if TQG)

$$\phi'_y = X_{\text{mode}}^{0 \rightarrow N} \quad \text{and} \quad \omega_n^\phi = c^{0 \rightarrow N} \cdot k_n \quad (22a)$$

$$\Theta'_y = X_{\text{mode}}^{N \rightarrow 2 \cdot N} \quad \text{and} \quad \omega_n^\Theta = c^{N \rightarrow 2 \cdot N} \cdot k_n \quad (22b)$$

Then,

$$\phi'_n(t, y) = \text{Re} \left\{ \phi_y \cdot \exp(-i \cdot \omega_n^\phi \cdot t) \right\} \quad (23a)$$

$$\Theta'_n(t, y) = \text{Re} \left\{ \Theta_y \cdot \exp(-i \cdot \omega_n^\Theta \cdot t) \right\} \quad (23b)$$

Linear tools

We know that the values are modelised with a wave hypothesis times a growth rate (imaginary part where $\sigma = k \cdot c_i$) because $\exp(i \cdot k(x - c \cdot t)) = \exp(i \cdot k(x - (c_r + c_i) \cdot t))$.

$$\psi', u', v' = A \cdot \exp(i \cdot k \cdot (x - c_r \cdot t)) \cdot \exp(\sigma \cdot t)$$

The energy of the system is basically the sum of the velocity squared that is,

$$\begin{aligned} E' &= u'^2 + v'^2 \\ &= A \cdot \exp(i \cdot k \cdot (x - c_r \cdot t)) \cdot \exp(\sigma \cdot t) \cdot \exp(i \cdot k \cdot (x - c_r \cdot t)) \cdot \exp(\sigma \cdot t) \end{aligned}$$

But if we drop the x, y dependency we get,

$$E' = \exp(2 \cdot \sigma \cdot t)$$

For the energy we can consider that,

$$E = \exp(-\sigma_i \cdot t)$$

Non-linear tools

In this part we compute Fourier coefficients of the non-linear TQG code. This will be an alternative solution to estimate the energy of the system.

$$\begin{aligned} c_k(t, y) &= \sum_i \psi(t, x_i, y) \cdot \cos(k \cdot x_i) \cdot \Delta x \\ s_k(t, y) &= \sum_i \psi(t, x_i, y) \cdot \sin(k \cdot x_i) \cdot \Delta x \end{aligned}$$

And,

$$\begin{aligned} A_k(t, y) &= \sqrt{c_k^2 + s_k^2} \\ \varphi_k &= \arctan \left(\frac{s_k}{c_k} \right) \end{aligned}$$

And,

$$\begin{aligned} \overline{A}_k(t) &= \int A_k(t, y) \cdot dy \\ \overline{\varphi}_k(t) &= \int \varphi_k(t, y) \cdot dy \end{aligned}$$

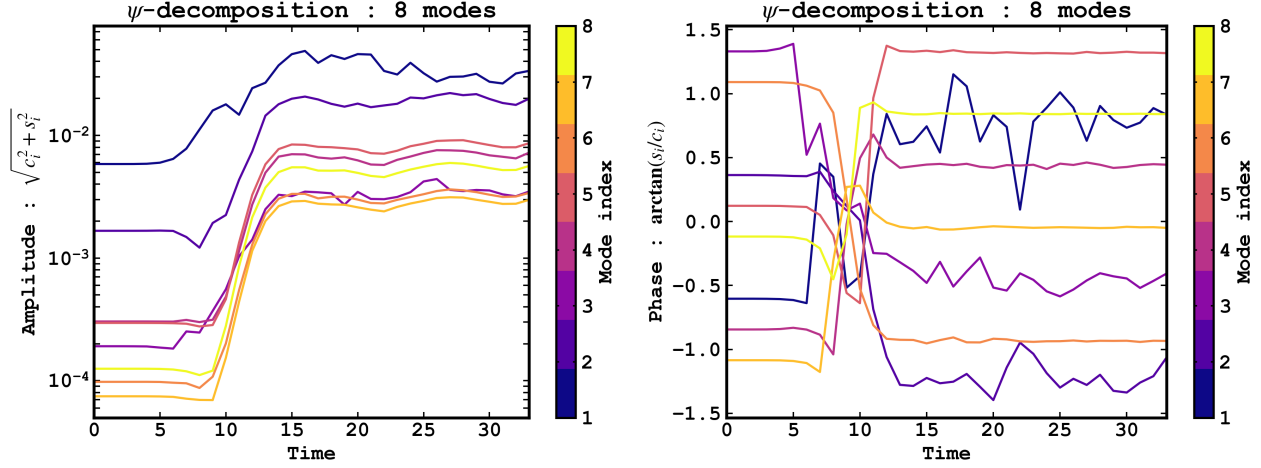


Fig. 2. Evolution of the amplitude and the phase of the Fourier decomposition.

4.2. Non-TQG Numerical solution

- Here's some values to set,

$$\bar{U}(y) = U_0 \cdot \exp(-y^2)$$

$$G_{12} = \frac{d\bar{\Theta}}{dy} = -2 \cdot y \cdot \Theta_0 \cdot \exp(-y^2)$$

$$G_{11} = \frac{d(\bar{q} - \bar{\Theta})}{dy} = \left[2 \cdot \bar{U} \cdot (1 - 2 \cdot y^2) + F_1^* \cdot \bar{U} + \beta \right] - \left[-2 \cdot y \cdot \Theta_0 \cdot \exp(-y^2) \right]$$

And associated to these values,

$$F_{11} = G_{11} \cdot \Delta y^2$$

$$F_1^* = \frac{1}{R_d^2}$$

Be aware : Do not make the confusion between F_1^* and F_{11} !

We can simplify equations (19a) and (19b) to find the non-TQG equation that is,

$$\bar{U}_n \cdot \left[\phi_{j+1} - 2 \cdot \phi_n + \phi_{j-1} - \phi_n \cdot K^2 \right] + \phi_n \cdot F_{1n} = c \cdot \left[\phi_{j+1} - 2 \cdot \phi_n + \phi_{j-1} - \phi_n \cdot K^2 \right]$$

That's really tempting to use A_{11} and B_{11} but ...

- **WARNING :** The $F_{1n} = G_{11} \cdot \Delta y^2 = \frac{d(\bar{q} - \bar{\Theta})}{dy} \cdot \Delta y^2$ term contains thermal terms that aren't in the QG problem : that makes the matrix A_{11} incorrect for this.
- **TO FIX IT :** We need to erase the $\frac{d\bar{\Theta}}{dy}$ that is equals to G_{12} . We add $G_{12} \cdot \Delta y^2$ to F_{1n} because the $\frac{d\bar{\Theta}}{dy}$ was initially subtracted to $\frac{d\bar{q}}{dy}$ in the TQG model. By addition, G_{12} vanishes. Here we disconnect the thermal term for the QG-solving.

So we get,

$$\boxed{\begin{aligned} \bar{U}_n \cdot \left[\phi_{j+1} - 2\phi_n + \phi_{j-1} - \phi_n K^2 \right] + \phi_n \cdot (F_{1n} + G_{12} \Delta y^2) \\ = c \cdot \left[\phi_{j+1} - 2\phi_n + \phi_{j-1} - \phi_n K^2 \right] \end{aligned}} \quad (24)$$

This is still an eigenvalue problem that can be solved using $\underline{X} = \phi_n$. We shall re-arrange A_{11} (let us call it A_{11}^*) when solving the QG model, but we can use the B_{11} matrix that is still the same (due to **WARNING** section).

$$\underline{A}_{11}^* \cdot \underline{X} = c \cdot \underline{B}_{11} \cdot \underline{X}$$

We use the same matrix than for the thermal solving : B_{11} and we use the modified version of A_{11} that is A_{11}^* . Here's a 3×3 example,

$$\begin{pmatrix} -\bar{U}_n(2+K^2) + F_{1n} + G_{12}\Delta y^2 & \bar{U}_n & 0 \\ \bar{U}_n & -\bar{U}_n(2+K^2) + F_{1n} + G_{12}\Delta y^2 & \bar{U}_n \\ 0 & \bar{U}_n & -\bar{U}_n(2+K^2) + F_{1n} + G_{12}\Delta y^2 \end{pmatrix} \times \phi_n = c_n \times \begin{pmatrix} -(2+K^2) & 1 & 0 \\ 1 & -(2+K^2) & 1 \\ 0 & 1 & -(2+K^2) \end{pmatrix} \times \phi_n$$

That is even simpler to construct than the previous eigenvalue problem. And the numerical problem can be still solved with python modules :

For instance `c, X = scipy.linalg.eig(A11*, B11)`. that will returns different eigenvalues and eigenvectors compared to the TQG-problem.

4.3. Flow stability

4.3.1. Linear : 2 cases [A RE REDIGER]

- **Configuration 1 :**

$$\bar{U}(y) = U_0 \cdot \exp(-y^2) \quad (25a)$$

$$\bar{\Theta}(y) = \Theta_0 \cdot \exp(-y^2) \quad (25b)$$

- **Configuration 2 :**

$$\bar{U}(y) = U_0 \cdot \exp(-y^2) \quad (26a)$$

$$\bar{\Theta}(y) = \Theta_0 \cdot \exp\left(-\frac{y^2}{L_*^2}\right) \quad (26b)$$

We first study the variation of 3 parameters (and their effect on the growth rates) with the **configuration 1** that are,

$$\begin{aligned} \beta &\in [0 ; 3] \\ F_1^* &= \frac{1}{R_d^2} \in [0 ; 12] \\ \frac{\Theta_0}{U_0} &\in [0 ; 2] \end{aligned}$$

Then for the **configuration 2** we need to make L_* vary and re-computes growth rates for each variation of paramters,

$$F_1^* = \frac{1}{R_d^2} \in [0 ; 12] \left. \begin{array}{l} \beta \in [0 ; 3] \\ \frac{\Theta_0}{U_0} \in [0 ; 2] \end{array} \right\} \text{ For } L_* = [0.5 ; 1 ; 1.5 ; 2]$$

Observations :

- Effect of L_* :
 1. Seems to regulate $\Delta = \sigma_{\text{TQG}} - \sigma_{\text{QG}}$.
 2. Critical values.
- Effect of β and F_1^* :
 1. Linearise σ and creates bulges (sometimes).
 2. Seems to control the rapidity of the decreasing.
- Effect of $\frac{\Theta_0}{U_0}$:
 1. Control the amplitude of the growth of the growth rates.
 2. Subsequently it controls also $\Delta = \sigma_{\text{TQG}} - \sigma_{\text{QG}}$.

4.4. 2D TQG numerical model

Inspired by (17a) and (17b) we can re-write the 2D equations for the TQG model,

$$(\bar{U} - c) \cdot \left(\frac{d^2 \phi}{dx^2} + \frac{d^2 \phi}{dy^2} - \phi \cdot k_d^2 \right) - \bar{U} \cdot \Theta + \phi \cdot G_{11} = 0 \quad (27a)$$

$$(\bar{U} - c) \cdot \Theta + \phi \cdot G_{12} = 0 \quad (27b)$$

If we discretise these equations we get,

$$\begin{aligned} (\bar{U}_n^j - c) \cdot \left(\frac{\phi_{n+1}^j - 2\phi_n^j + \phi_{n-1}^j}{\Delta x^2} + \frac{\phi_n^{j+1} - 2\phi_n^j + \phi_n^{j-1}}{\Delta y^2} - \phi_n^j \cdot k_d^2 \right) - \bar{U}_n^j \cdot \Theta + \phi_n^j \cdot G_{11} &= 0 \\ (\bar{U}_n^j - c) \cdot \Theta + \phi_n^j \cdot G_{12} &= 0 \end{aligned}$$

Then re-arrange,

$$\begin{aligned} \bar{U}_n^j \cdot \left(\frac{\phi_{n+1}^j - 2\phi_n^j + \phi_{n-1}^j}{\Delta x^2} + \frac{\phi_n^{j+1} - 2\phi_n^j + \phi_n^{j-1}}{\Delta y^2} - \phi_n^j \cdot k_d^2 \right) - \bar{U}_n^j \cdot \Theta + \phi_n^j \cdot G_{11} \\ = c \cdot \left(\frac{\phi_{n+1}^j - 2\phi_n^j + \phi_{n-1}^j}{\Delta x^2} + \frac{\phi_n^{j+1} - 2\phi_n^j + \phi_n^{j-1}}{\Delta y^2} - \phi_n^j \cdot k_d^2 \right) \\ \bar{U}_n^j \cdot \Theta + \phi_n^j \cdot G_{12} = c \cdot \Theta \end{aligned}$$

4.4.1. $\Delta x = \Delta y = \Delta h$

$$\begin{aligned} \bar{U}_n^j \cdot \left(\frac{\phi_{n+1}^j - 2.\phi_n^j + \phi_{n-1}^j}{\Delta h^2} + \frac{\phi_n^{j+1} - 2.\phi_n^j + \phi_n^{j-1}}{\Delta h^2} - \phi_n^j.k_d^2 \right) - \bar{U}_n^j.\Theta + \phi_n^j.G_{11} \\ = c. \left(\frac{\phi_{n+1}^j - 2.\phi_n^j + \phi_{n-1}^j}{\Delta h^2} + \frac{\phi_n^{j+1} - 2.\phi_n^j + \phi_n^{j-1}}{\Delta h^2} - \phi_n^j.k_d^2 \right) \\ \bar{U}_n^j.\Theta + \phi.G_{12} = c.\Theta \end{aligned}$$

We multiply by Δh^2 (only the 1st equation) and we get,

$$\begin{aligned} \bar{U}_n^j \cdot \left(\phi_{n+1}^j - 2.\phi_n^j + \phi_{n-1}^j + \phi_n^{j+1} - 2.\phi_n^j + \phi_n^{j-1} - \phi_n^j.k_d^2.\Delta h^2 \right) - \bar{U}_n^j.\Delta h^2.\Theta + \phi_n^j.G_{11}.\Delta h^2 \\ = c. \left(\phi_{n+1}^j - 2.\phi_n^j + \phi_{n-1}^j + \phi_n^{j+1} - 2.\phi_n^j + \phi_n^{j-1} - \phi_n^j.k_d^2.\Delta h^2 \right) \\ \bar{U}_n^j.\Theta + \phi.G_{12} = c.\Theta \end{aligned}$$

We shall now introduce : $\bar{U}_n^j.\Delta h^2 = \bar{V}_n^j$, $G_{11}.\Delta h^2 = F_{11}$, $k_d^2.\Delta h^2 = K^2$ and so,

$$\bar{U}_n^j \cdot \left(\phi_{n+1}^j - 4.\phi_n^j + \phi_{n-1}^j + \phi_n^{j+1} + \phi_n^{j-1} - \phi_n^j.K^2 \right) - \bar{V}_n^j.\Theta + \phi_n^j.F_{11} \quad (28a)$$

$$= c. \left(\phi_{n+1}^j - 4.\phi_n^j + \phi_{n-1}^j + \phi_n^{j+1} + \phi_n^{j-1} - \phi_n^j.K^2 \right) \quad (28b)$$

$$\bar{U}_n^j.\Theta + \phi.G_{12} = c.\Theta \quad (28c)$$

So that's an eigenvalue problem such that $\underline{\underline{A}}.X = c.\underline{\underline{B}}.X$ and $X = \begin{pmatrix} \phi \\ \Theta \end{pmatrix}$,

$$\begin{pmatrix} A_{11} & A_{12} \\ A_{21} & A_{22} \end{pmatrix} \times \begin{pmatrix} \phi \\ \Theta \end{pmatrix} = c. \begin{pmatrix} B_{11} & B_{12} \\ B_{21} & B_{22} \end{pmatrix} \times \begin{pmatrix} \phi \\ \Theta \end{pmatrix} \quad (29)$$

With the matrix A

$$\begin{aligned}
\underline{\underline{A}} &= \begin{pmatrix} A_{11} & A_{12} \\ A_{21} & A_{22} \end{pmatrix} \\
A_{11} &= \begin{bmatrix} -\bar{U}_n^j \cdot (4 + K^2 + F_{11}) & 1 & 0 & 1 \\ 1 & -\bar{U}_n^j \cdot (4 + K^2 + F_{11}) & 1 & 0 \\ 0 & 1 & -\bar{U}_n^j \cdot (4 + K^2 + F_{11}) & 1 \\ 1 & 0 & 1 & -\bar{U}_n^j \cdot (4 + K^2 + F_{11}) \end{bmatrix} \\
A_{12} &= \begin{bmatrix} -\bar{V}_n^j & 0 & 0 & 0 \\ 0 & -\bar{V}_n^j & 0 & 0 \\ 0 & 0 & -\bar{V}_n^j & 0 \\ 0 & 0 & 0 & -\bar{V}_n^j \end{bmatrix} \\
A_{21} &= \begin{bmatrix} G_{12} & 0 & 0 & 0 \\ 0 & G_{12} & 0 & 0 \\ 0 & 0 & G_{12} & 0 \\ 0 & 0 & 0 & G_{12} \end{bmatrix} \\
A_{22} &= \begin{bmatrix} \bar{U}_n^j & 0 & 0 & 0 \\ 0 & \bar{U}_n^j & 0 & 0 \\ 0 & 0 & \bar{U}_n^j & 0 \\ 0 & 0 & 0 & \bar{U}_n^j \end{bmatrix}
\end{aligned}$$

And with the matrix B

$$\begin{aligned}
\underline{\underline{B}} &= \begin{pmatrix} B_{11} & B_{12} \\ B_{21} & B_{22} \end{pmatrix} \\
&= \left(\begin{bmatrix} -(4 + K^2) & 1 & 0 & 1 \\ 1 & -(4 + K^2) & 1 & 0 \\ 0 & 1 & -(4 + K^2) & 1 \\ 1 & 0 & 1 & -(4 + K^2) \end{bmatrix} \begin{bmatrix} 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 \end{bmatrix} \right) \\
&\quad \left(\begin{bmatrix} 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 \\ 0 & 0 & 0 & 0 \end{bmatrix} \begin{bmatrix} 1 & 0 & 0 & 0 \\ 0 & 1 & 0 & 0 \\ 0 & 0 & 1 & 0 \\ 0 & 0 & 0 & 1 \end{bmatrix} \right)
\end{aligned}$$

The **Fig. 3.** shows snapshots of the 2D version of the TQG linear solver. To obtain ψ and Θ we need to re-construct our function, as done previously, we re construct the perturbations,

$$\begin{aligned}
\phi'_{xy} &= X_{\text{mode}}^{0 \rightarrow N} \quad \text{and} \quad \omega_n^\phi = c^{0 \rightarrow N} \cdot k_n \\
\Theta'_{xy} &= X_{\text{mode}}^{N \rightarrow 2.N} \quad \text{and} \quad \omega_n^\Theta = c^{N \rightarrow 2.N} \cdot k_n
\end{aligned}$$

Then

$$\begin{aligned}
\phi'_n(t, x, y) &= \text{Re} \left\{ \phi'_{xy} \cdot \exp(-i \cdot \omega_n^\phi \cdot t) \right\} \\
\Theta'_n(t, x, y) &= \text{Re} \left\{ \Theta'_{xy} \cdot \exp(-i \cdot \omega_n^\Theta \cdot t) \right\}
\end{aligned}$$

And to have the full value of ϕ and Θ we need to re add mean current $\Theta = \overline{\Theta} + \overline{\Theta'}$ for instance,

$$\Theta = \text{Re} \left\{ \Theta'_{xy} \cdot \exp(-i \cdot \omega_n^\Theta \cdot t) \right\} + \Theta_0 \cdot \exp(-y^2)$$

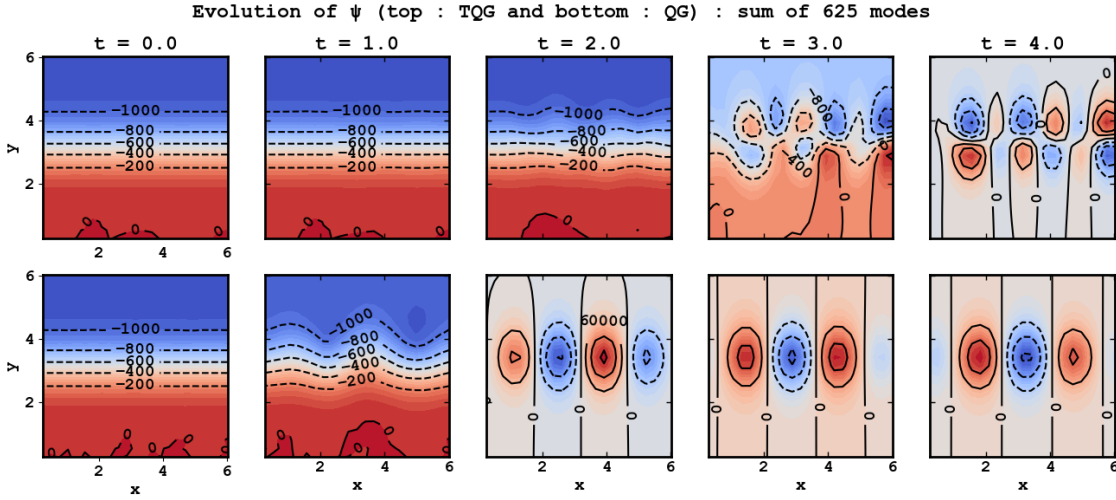


Fig. 3. Snapshot of streamfunction from `TQG_solve_v3_bis_JULIE.py` code.

4.5. Non-Linear TQG model

This part is done with the TQG spectral code used by [Flierl et al., 1987] modified by X.Carton for the thermal version.

5. Appendix

5.1. Validation of `TQG_solve_v2_bis_TARANIS.py`

Here we propose to compare the code detailed below with the Fortran code developed by Xavier Carton (as a reference because it is validated with respect to [Flierl et al., 1987]). The comparison of the 2 codes is presented in **Fig. 4.** and **Fig. 5.**

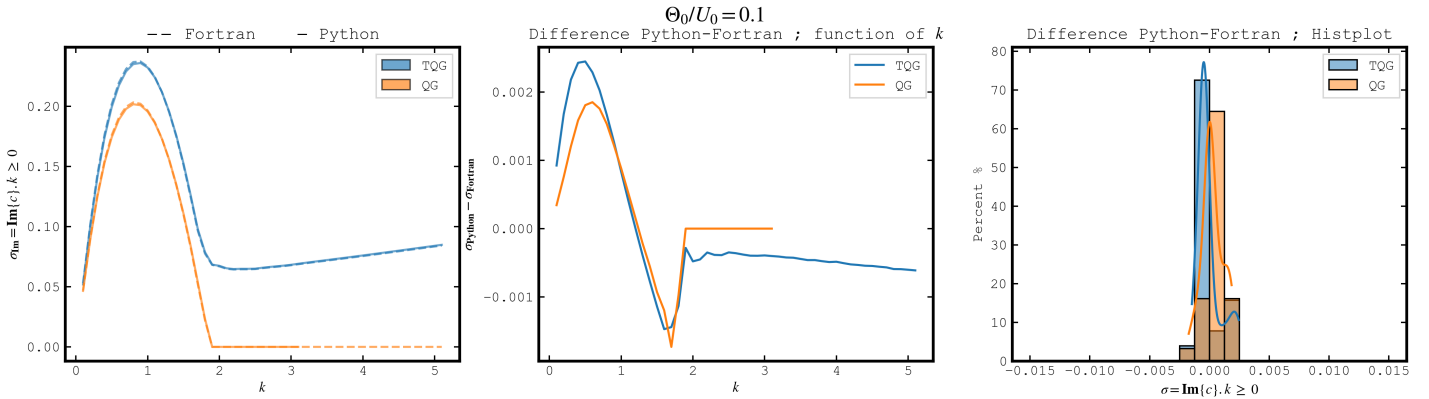


Fig. 4. Experience Taranis : Case where $\Theta_0/U_0 = 0.1$. **Left** : growth rates comparison between the fortran (straight line) and the python (dashed line) code for TQG and QG cases. **Center** : Difference between Python and Fortran codes for TQG and QG growth rates. **Right** : Histplot of the difference where we see a Gaussian tendency for the two cases.

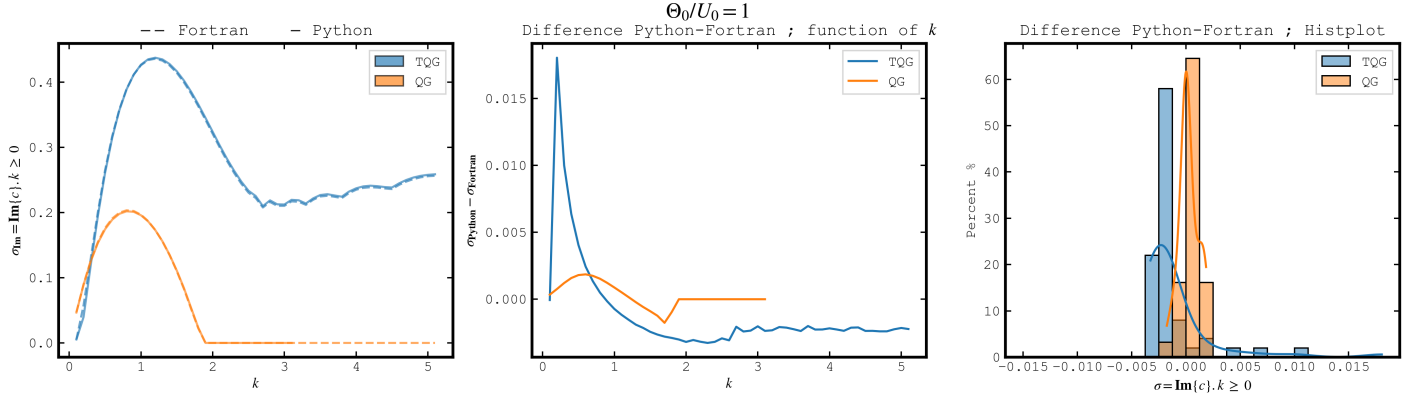


Fig. 5. Experience Taranis : Case where $\Theta_0/U_0 = 1$. **Left** : growth rates comparison between the fortran (straight line) and the python (dashed line) code for TQG and QG cases. **Center** : Difference between Python and Fortran codes for TQG and QG growth rates. **Right** : Histplot of the difference where we see a Gaussian tendency for the two cases.

Conclusion : The 2 codes are giving almost the same solution. The maximum difference between the 2 codes is around $2.5 \times 10^{-3} \sigma_{lm}$.

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