On the guess consistency in multi-incremental multi-resolution variational data assimilation

Nicolas Baillot d'Étiaux[1], Benjamin Ménétrier[2], Selime Gürol[3], and Yann Michel[4]

[1]CNRM, Université de Toulouse, Météo-France, CNRS, Toulouse, France
[2]IRIT, ...
[2]CERFACS, ...
[4]Météo-France, ...

Correspondence: Benjamin Ménétrier (benjamin.menetrier@irit.fr)

Abstract. Variational Data Assimilation (DA) schemes are often used to adress high dimensional non-linear problems in operational applications in the Numerical Wheather Prediction (NWP) domain. Because of the high computational cost of such minimization problems, various methods can be applied to improve the convergence at a reasonable numerical cost. One of these methods currently applied in operational DA schemes is the multi-incremental approach that consists in solving a succession of linearized versions of the original non-linear problem in several outer loops, by using well known algorithms to ensure the convergence of the linear problem at the inner loop level, and using the solution of the inner loops to update the problem at each outer loop. In order to save computational cost, the multi-incremental multi-resolution method consists in starting the minimization at a lower resolution than the original one, and increasing it at the outer loop level until the full resolution of the problem. In such a scheme, the way to compute the new guess at each outer loop from the previous iterations is crucial. We adress the question of the guess consistency in the standard method currently used in operational systems, and also present a new method which ensures the guess consistency and need simpler calculations.

1 Introduction

intro...

2 Data Assimilation Problem

In Data Assimilation (DA), one wants to minimize the following non linear cost function representing the ability of a model state to be compatible with observations:

$$\mathcal{J}(\mathbf{x}) = \frac{1}{2}\left(\mathbf{x}-\mathbf{x}^b\right)^\mathrm{T}\mathbf{B}^{-1}\left(\mathbf{x}-\mathbf{x}^b\right) + \frac{1}{2}\left(\mathbf{y}^o-\mathcal{H}(\mathbf{x})\right)^\mathrm{T}\mathbf{R}^{-1}\left(\mathbf{y}^o-\mathcal{H}(\mathbf{x})\right), \tag{1}$$

where $\mathbf{x}\in\mathbb{R}^n$ is the state in model space of size n, $\mathbf{x}^b\in\mathbb{R}^n$ is the background state, $\mathbf{B}\in\mathbb{R}^{n\times n}$ is the background error covariance matrix, $\mathbf{y}^o\in\mathbb{R}^p$ is the observation vector in observation space of size p (note that in general $p<n$), $\mathbf{R}\in\mathbb{R}^{p\times p}$ is the observation error covariance matrix, and $\mathcal{H}:\mathbb{R}^n\rightarrow\mathbb{R}^p$ is the observation operator which maps the model space to the observation space.

2.1 Problem linearization

In general the observation operator is nonlinear and can be linearized around a guess state $\mathbf{x}_k^g \in \mathbb{R}^n$ so that: $\mathcal{H}(\mathbf{x}) \approx \mathcal{H}(\mathbf{x}_k^g) + \mathbf{H}_k \delta\mathbf{x}_k$ for $\mathbf{x} \approx \mathbf{x}_k^g$, defining the increment $\delta\mathbf{x}_k = \mathbf{x} - \mathbf{x}_k^g$, and where $\mathbf{H}_k \in \mathbb{R}^{p\times m}$ is the observation operator linearized around the guess state: $H_{k,ij} = \left.\frac{\partial \mathcal{H}_i}{\partial x_j}\right|_{\mathbf{x}=\mathbf{x}_k^g}$. Instead of minimizing the full cost function $\mathcal{J}(\mathbf{x})$, it is now possible to minimize successive quadratic approximations around successive guess states:

$$J(\delta\mathbf{x}_k) = \frac{1}{2}\left(\delta\mathbf{x}_k - \delta\mathbf{x}_k^b\right)^{\mathrm{T}} \mathbf{B}^{-1}\left(\delta\mathbf{x}_k - \delta\mathbf{x}_k^b\right) + \frac{1}{2}\left(\mathbf{d}_k - \mathbf{H}_k\delta\mathbf{x}_k\right)^{\mathrm{T}} \mathbf{R}^{-1}\left(\mathbf{d}_k - \mathbf{H}_k\delta\mathbf{x}_k\right) \tag{2}$$

where k indicates the k^{th} iteration (hereafter these iterations are called "outer loops" since the minimization of the successive approximations are realized using well known iterative solvers such as lanczos alorithms . We call "inner loops" the iterations of these algorithms), $\delta\mathbf{x}_k^b = \mathbf{x}^b - \mathbf{x}_k^g$ is the background increment and $\mathbf{d}_k = \mathbf{y}^o - \mathcal{H}(\mathbf{x}_k^g)$ is the innovation vector.

Setting the gradient of $J(\delta\mathbf{x}_k)$ to zero gives the analysis increment $\delta\mathbf{x}_k^a$:

$$\begin{aligned}
&\mathbf{B}^{-1}\left(\delta\mathbf{x}_k^a - \delta\mathbf{x}_k^b\right) - \mathbf{H}_k^{\mathrm{T}}\mathbf{R}^{-1}\left(\mathbf{d}_k - \mathbf{H}_k\delta\mathbf{x}_k^a\right) = 0 \\
\Leftrightarrow\ &\left(\mathbf{B}^{-1} + \mathbf{H}_k^{\mathrm{T}}\mathbf{R}^{-1}\mathbf{H}_k\right)\delta\mathbf{x}_k^a = \mathbf{B}^{-1}\delta\mathbf{x}_k^b + \mathbf{H}_k^{\mathrm{T}}\mathbf{R}^{-1}\mathbf{d}_k \\
\Leftrightarrow\ &\boxed{\mathbf{A}_k^{\mathbf{x}}\delta\mathbf{x}_k^a = \mathbf{b}_k^{\mathbf{x}}}
\end{aligned} \tag{3}$$

with $\mathbf{A}_k^{\mathbf{x}} \in \mathbb{R}^{n\times n}$ and the right hand side $\mathbf{b}_k^{\mathbf{x}} \in \mathbb{R}^n$ defined as:

$$\mathbf{A}_k^{\mathbf{x}} = \mathbf{B}^{-1} + \mathbf{H}_k^{\mathrm{T}}\mathbf{R}^{-1}\mathbf{H}_k, \tag{4}$$

$$\mathbf{b}_k^{\mathbf{x}} = \mathbf{B}^{-1}\delta\mathbf{x}_k^b + \mathbf{H}_k^{\mathrm{T}}\mathbf{R}^{-1}\mathbf{d}_k. \tag{5}$$

The problem can now be solved using Gauss-Newton algorithm. It is very common to use the background state as a guess for the first iteration $k=1$ ($\mathbf{x}_1^g = \mathbf{x}^b$), and then for $k>1$, the analysis of the previous iteration is used to define the guess ($\mathbf{x}_k^g = \mathbf{x}_{k-1}^a$). Thus, the first background increment is $\delta\mathbf{x}_1^b = \mathbf{x}_1^g - \mathbf{x}^b = 0$, and the following ones can be computed as:

$$\begin{aligned}
\delta\mathbf{x}_k^b &= \mathbf{x}^b - \mathbf{x}_k^g, \\
&= \mathbf{x}^b - \mathbf{x}_{k-1}^a, \\
&= \mathbf{x}^b - \left(\mathbf{x}_{k-1}^g + \delta\mathbf{x}_{k-1}^a\right), \\
&= \delta\mathbf{x}_{k-1}^b - \delta\mathbf{x}_{k-1}^a,
\end{aligned} \tag{6}$$

which can be combined recursively to yield:

$$\delta\mathbf{x}_k^b = -\sum_{i=1}^{k-1}\delta\mathbf{x}_i^a. \tag{7}$$

In general, the condition number of this problem is poor, and one has to use preconditionning techniques to improve it.

2.2 Preconditionning

In this section we describe the square root $\mathbf{B}$ preconditionning, which is widely used in DA. The $\mathbf{B}$ matrix have the important property of being positive definite, so that there is an infinity of square-roots $\mathbf{U}$ verifying $\mathbf{B} = \mathbf{U}\mathbf{U}^{\mathrm{T}}$. The square root $\mathbf{B}$ preconditionning consists in defining a new control variable $\delta\mathbf{v}_k = \mathbf{U}^{\mathrm{T}}\mathbf{B}^{-1}\delta\mathbf{x}_k$, so that the linear system (3) can now be written in control space as $\mathbf{A}_k^{\mathbf{v}}\delta\mathbf{v}_k^a = \mathbf{b}_k^{\mathbf{v}}$ with:

$$\mathbf{A}_k^{\mathbf{v}} = \mathbf{I}_m + \mathbf{U}^{\mathrm{T}}\mathbf{H}_k^{\mathrm{T}}\mathbf{R}^{-1}\mathbf{H}_k\mathbf{U}, \tag{8}$$

$$\mathbf{b}_k^{\mathbf{v}} = \delta\mathbf{v}_k^b + \mathbf{U}^{\mathrm{T}}\mathbf{H}_k^{\mathrm{T}}\mathbf{R}^{-1}\mathbf{d}_k. \tag{9}$$

Using this technique allows to recursively solve the system without using $\mathbf{B}^{-1}$ which is, in general, not available due to its high dimension, even if it is needed in general to compute the right-hand side $\mathbf{b}_k^{\mathbf{v}}$: $\mathbf{U}^{\mathrm{T}}\mathbf{B}^{-1}$ can be applied on both side of equation (7), leading to:

$$\delta\mathbf{v}_k^b = -\sum_{i=1}^{k-1}\delta\mathbf{v}_i^a, \tag{10}$$

which can be used to compute the right hand side $\mathbf{b}_k^{\mathbf{v}}$ without requiring $\mathbf{B}^{-1}$.

2.3 Changing the resolution between the outer loops

In special cases, the background error covariance matrix can be updated between outer iterations defining $\mathbf{B}_k$, and its square-root $\mathbf{U}_k$. In this case, it is not systematically possible to compute the background increment without using $\mathbf{B}^{-1}$. One example of such a scheme is the multi-incremental multi-resolution approach, in which the resolution increases at each outer loop for computational efficiency, and therefore, the $\mathbf{B}$ matrix depends on k. In this case, Equation (10) is valid and one can obtain the background increment as follows:

$$\begin{aligned}\delta\mathbf{v}_k^b &= -\mathbf{U}_k^{\mathrm{T}}\mathbf{B}_k^{-1}\sum_{i=1}^{k-1}\delta\mathbf{x}_i^a,\\ &= -\sum_{i=1}^{k-1}\mathbf{U}_k^{\mathrm{T}}\mathbf{B}_k^{-1}\mathbf{U}_i\delta\mathbf{v}_i^a.\end{aligned} \tag{11}$$

It should be emphasized that if $\mathbf{U}_k^{\mathrm{T}}\mathbf{B}_k^{-1}\mathbf{U}_i\delta\mathbf{v}_i^a \neq \delta\mathbf{v}_i^a$, equation (10) cannot be used consistently. To realize the change of resolution, one needs to use interpolators in model space $\mathbf{T}_{i\to k}^{\mathbf{x}} \in \mathbb{R}^{n_k\times n_i}$ and in control space $\mathbf{T}_{i\to k}^{\mathbf{v}} \in \mathbb{R}^{m_k\times m_i}$ from the resolution $\mathcal{R}_i$ to $\mathcal{R}_k$, where n_k and m_k respectively denotes the size of the model space and the control space. For clarity, we now assume that the resolutions are stricly increasing: for $i < k$, $n_i < n_k$ and $m_i < m_k$, and that the full resolution is obtained at the last iteration K. We define two interpolators from resolution $\mathcal{R}_i$ to resolution $\mathcal{R}_k$:

- $\mathbf{T}_{i\to k}^{\mathbf{x}} \in \mathbb{R}^{n_k\times n_i}$ in model space,
- $\mathbf{T}_{i\to k}^{\mathbf{v}} \in \mathbb{R}^{m_k\times m_i}$ in control space,

A special class of interpolators called "transitive interpolators" have three extra properties:

– Upscaling transitivity: for $n_i < n_j$ and $n_i < n_k$:

$$\mathbf{T}^{\mathbf{x}}_{j\to k}\mathbf{T}^{\mathbf{x}}_{i\to j} = \mathbf{T}^{\mathbf{x}}_{i\to k} \tag{12}$$

– Downscaling transitivity: for $n_i < n_j < n_k$:

$$\mathbf{T}^{\mathbf{x}}_{j\to i}\mathbf{T}^{\mathbf{x}}_{k\to j} = \mathbf{T}^{\mathbf{x}}_{k\to i} \tag{13}$$

– Right-inverse: for $n_i < n_k$

$$\mathbf{T}^{\mathbf{x}}_{k\to i}\mathbf{T}^{\mathbf{x}}_{i\to k} = \mathbf{I}_{n_i} \tag{14}$$

and similarly for $\mathbf{T}^{\mathbf{v}}_{i\to k}$ in control space, replacing n with m.

Associated to the various resolution, we qualify a $\mathbf{B}$ family as "projective" if the low-resolution members can be defined as a projection of the high-resolution one, using transitive interpolators. For $n_i < n_k$, that would mean:

$$\mathbf{B}_k\mathbf{T}^{\mathbf{x}}_{i\to k} = \mathbf{T}^{\mathbf{x}}_{i\to k}\mathbf{B}_i \tag{15}$$

and for the square-root of $\mathbf{B}$:

$$\mathbf{U}_k\mathbf{T}^{\mathbf{v}}_{i\to k} = \mathbf{T}^{\mathbf{x}}_{i\to k}\mathbf{U}_i \tag{16}$$

The multi-resolution problem should be solved with the following requirements in mind:

– The background $\mathbf{x}^b$ is provided at full resolution, but it can be simplified at resolution $\mathcal{R}_k$:

$$\mathbf{x}^b_k = \mathbf{T}^{\mathbf{x}}_{K\to k}\mathbf{x}^b \tag{17}$$

– A full resolution guess denoted $\mathbf{x}^{g+}_k$ has to be computed at each outer iteration to run model trajectories used in the operators linearization. This full resolution guess can be simplified at resolution $\mathcal{R}_k$ to give the actual guess of the outer iteration k:

$$\mathbf{x}^g_k = \mathbf{T}^{\mathbf{x}}_{K\to k}\mathbf{x}^{g+}_k \tag{18}$$

– Only δ-quantities should be interpolated to higher resolution, and then possibly added to full quantities at full resolution.

3 Guess consistency

In the linear systems solved at each outer iteration, the the full resolution guess $\mathbf{x}_k^{g+}$ appears for two distinct purposes:

– First, it is explicitely defined to be used as the linearization state for the observation operator at each outer loops and to compute the innovation $\mathbf{d}_k$. The first guess for $k = 1$ is taken as the background state, also provided at full resolution $\mathbf{x}_1^{g+} = \mathbf{x}^b$. At the end of iteration k, without any loss of generality, we can define the analysis increment at full resolution $\delta\mathbf{x}_{k-1}^{a+}$ that updates the full resolution guess:

$$\mathbf{x}_k^{g+} = \mathbf{x}_{k-1}^{g+} + \delta\mathbf{x}_{k-1}^{a+} \tag{19}$$

The way the analysis increment at full resolution $\delta\mathbf{x}_{k-1}^{a+}$ is obtained from the products of previous outer iterations does not matter at this point.

– Second, it is implicitly present in the first term of the right-hand side:

$$\begin{aligned}\delta\mathbf{v}_k^b &= \mathbf{U}_k^\mathrm{T}\mathbf{B}_k^{-1}\delta\mathbf{x}_k^b \\ &= \mathbf{U}_k^\mathrm{T}\mathbf{B}_k^{-1}\left(\mathbf{x}_k^b - \mathbf{x}_k^g\right) \\ &= \mathbf{U}_k^\mathrm{T}\mathbf{B}_k^{-1}\mathbf{T}_{K\rightarrow k}^{\mathbf{x}}\left(\mathbf{x}^b - \mathbf{x}_k^{g+}\right)\end{aligned} \tag{20}$$

The question of the consistency between these two occurences of the guess state in the minimization is crucial and is detailed in the following sections.

3.1 Theoretical method

In the "theoretical" method, one assumes that $\mathbf{B}_k^{-1}$ is available and can be used to compute the increment $\delta\mathbf{v}_k^b$ explicitly from $\mathbf{x}_k^{g+}$ using equations (20). There is no requirement on the expression of the analysis increment at full resolution $\delta\mathbf{x}_{k-1}^{a+}$.

3.2 Standard method

In the "standard" method, which is currently used in operational multi-incremental multi-resolution schemes, $\mathbf{B}_k^{-1}$ is not available and the first term of the right-hand side is computed separately, using transformed versions of equation (10) with appropriate interpolations:

$$\boxed{\delta\mathbf{v}_k^b = -\sum_{i=1}^{k-1}\mathbf{T}_{i\rightarrow k}^{\mathbf{v}}\delta\mathbf{v}_i^a} \tag{21}$$

This additional constraint imposes a unique expression for the analysis increment at full resolution $\delta\mathbf{x}_{k-1}^{a+}$, if the guess consistency has to be maintained.

3.2.1 General case

Using equation (19) and the fact that the first full resolution guess is taken as the background state, the full resolution guess at iteration k can be expressed as:

$$\mathbf{x}_k^{g+} = \mathbf{x}^b + \sum_{i=1}^{k-1} \delta\mathbf{x}_i^{a+} \tag{22}$$

which is equivalent to:

$$\mathbf{x}^b - \mathbf{x}_k^{g+} = -\sum_{i=1}^{k-1} \delta\mathbf{x}_i^{a+} \tag{23}$$

This result can be introduced into equation (20) to get the background increment as a function of the analysis increment at full resolution $\delta\mathbf{x}_i^{a+}$:

$$\delta\mathbf{v}_k^b = -\mathbf{U}_k^\mathrm{T}\mathbf{B}_k^{-1}\mathbf{T}_{K\to k}^{\mathbf{x}} \sum_{i=1}^{k-1} \delta\mathbf{x}_i^{a+} \tag{24}$$

Comparing equations (21) and (24), the guess consistency is maintained if:

$$\mathbf{U}_k^\mathrm{T}\mathbf{B}_k^{-1}\mathbf{T}_{K\to k}^{\mathbf{x}} \sum_{i=1}^{k-1} \delta\mathbf{x}_i^{a+} = \sum_{i=1}^{k-1} \mathbf{T}_{i\to k}^{\mathbf{v}}\delta\mathbf{v}_i^a$$

$$\Leftrightarrow \mathbf{T}_{K\to k}^{\mathbf{x}} \sum_{i=1}^{k-1} \delta\mathbf{x}_i^{a+} = \mathbf{U}_k \sum_{i=1}^{k-1} \mathbf{T}_{i\to k}^{\mathbf{v}}\delta\mathbf{v}_i^a$$

$$\Leftrightarrow \boxed{\mathbf{T}_{K\to k}^{\mathbf{x}}\delta\mathbf{x}_{k-1}^{a+} = \mathbf{U}_k \sum_{i=1}^{k-1} \mathbf{T}_{i\to k}^{\mathbf{v}}\delta\mathbf{v}_i^a - \mathbf{T}_{K\to k}^{\mathbf{x}} \sum_{i=1}^{k-2} \delta\mathbf{x}_i^{a+}} \tag{25}$$

To understand this result, one needs to distinguish between two cases according to the number of outer loops to be realized: if $K = 2$, equation (25) corresponding to the last iteration $k = K = 2$ becomes $\delta\mathbf{x}_1^{a+} = \mathbf{U}_2\mathbf{T}_{1\to 2}^{\mathbf{v}}\delta\mathbf{v}_1^a$ leading to an explicit expression of $\delta\mathbf{x}_1^{a+}$. In the case where $K > 2$, equation (25) can be solved explicitly if $\mathbf{T}_{K\to k}^{\mathbf{x}}$ has a known right-inverse denoted $(\mathbf{T}_{K\to k}^{\mathbf{x}})_\text{right}^{-1}$, such that $\mathbf{T}_{K\to k}^{\mathbf{x}}(\mathbf{T}_{K\to k}^{\mathbf{x}})_\text{right}^{-1} = \mathbf{I}_{n_k}$. In this case, equation (25) becomes:

$$\delta\mathbf{x}_{k-1}^{a+} = (\mathbf{T}_{K\to k}^{\mathbf{x}})_\text{right}^{-1}\left(\mathbf{U}_k \sum_{i=1}^{k-1} \mathbf{T}_{i\to k}^{\mathbf{v}}\delta\mathbf{v}_i^a - \mathbf{T}_{K\to k}^{\mathbf{x}} \sum_{i=1}^{k-2} \delta\mathbf{x}_i^{a+}\right) \tag{26}$$

Not that if this right-inverse exists, its unicity depends on the rank of the kernel of $\mathbf{T}_{K\to k}^{\mathbf{x}}$: if $\delta\mathbf{x}_{k-1}^{a+}$ is a solution of equation (25) and $\mathbf{u} \in \mathrm{Ker}\left(\mathbf{T}_{K\to k}^{\mathbf{x}}\right)$, then $\left(\delta\mathbf{x}_{k-1}^{a+} + \mathbf{u}\right)$ is also a solution.

3.2.2 Simplified standard method

The right-hand side of equation (31) can be split in order to extract the term coming from outer iteration $k-1$:

$$\delta\mathbf{x}_{k-1}^{a+} = \mathbf{T}_{k\to K}^{\mathbf{x}}\mathbf{U}_k\mathbf{T}_{k-1\to k}^{\mathbf{v}}\delta\mathbf{v}_{k-1}^a + \mathbf{T}_{k\to K}^{\mathbf{x}} \sum_{i=1}^{k-2} \left(\mathbf{U}_k\mathbf{T}_{i\to k}^{\mathbf{v}}\delta\mathbf{v}_i^a - \mathbf{T}_{K\to k}^{\mathbf{x}}\delta\mathbf{x}_i^{a+}\right) \tag{27}$$

If the $\mathbf{B}$ family is projective, then:

$$\mathbf{T}^{\mathbf{x}}_{k\rightarrow K}\mathbf{U}_k\mathbf{T}^{\mathbf{v}}_{k-1\rightarrow k} = \mathbf{T}^{\mathbf{x}}_{k\rightarrow K}\mathbf{T}^{\mathbf{x}}_{k-1\rightarrow k}\mathbf{U}_{k-1} = \mathbf{T}^{\mathbf{x}}_{k-1\rightarrow K}\mathbf{U}_{k-1} \tag{28}$$

so a simplified expression of $\delta\mathbf{x}^{a+}_{k-1}$ is:

$$\boxed{\delta\mathbf{x}^{a+}_{k-1} = \mathbf{T}^{\mathbf{x}}_{k-1\rightarrow K}\mathbf{U}_{k-1}\delta\mathbf{v}^{a}_{k-1}} \tag{29}$$

that verifies (31) since both terms inside the summation cancel each other:

$$\begin{aligned}\mathbf{U}_k\mathbf{T}^{\mathbf{v}}_{i\rightarrow k}\delta\mathbf{v}^{a}_{i} - \mathbf{T}^{\mathbf{x}}_{K\rightarrow k}\delta\mathbf{x}^{a+}_{i} &= \mathbf{U}_k\mathbf{T}^{\mathbf{v}}_{i\rightarrow k}\delta\mathbf{v}^{a}_{i} - \mathbf{T}^{\mathbf{x}}_{K\rightarrow k}\mathbf{T}^{\mathbf{x}}_{i\rightarrow K}\mathbf{U}_i\delta\mathbf{v}^{a}_{i}\\ &= \left(\mathbf{U}_k\mathbf{T}^{\mathbf{v}}_{i\rightarrow k} - \mathbf{T}^{\mathbf{x}}_{i\rightarrow k}\mathbf{U}_i\right)\delta\mathbf{v}^{a}_{i}\\ &= 0\end{aligned} \tag{30}$$

Equation (29) now estimates $\delta\mathbf{x}^{a+}_{k-1}$ using results from outer iterations $k-1$ only and this expression is refered to as "simplified expression" in the following.

3.2.3 Corrected standard method

If one uses transitive interpolators, the right inverse of $\mathbf{T}^{\mathbf{x}}_{K\rightarrow k}$ exists and is defined as $\mathbf{T}^{\mathbf{x}}_{k\rightarrow K}$, so that:

$$\boxed{\delta\mathbf{x}^{a+}_{k-1} = \mathbf{T}^{\mathbf{x}}_{k\rightarrow K}\left(\mathbf{U}_k\sum_{i=1}^{k-1}\mathbf{T}^{\mathbf{v}}_{i\rightarrow k}\delta\mathbf{v}^{a}_{i} - \mathbf{T}^{\mathbf{x}}_{K\rightarrow k}\sum_{i=1}^{k-2}\delta\mathbf{x}^{a+}_{i}\right)} \tag{31}$$

Equation (31) estimates $\delta\mathbf{x}^{a+}_{k-1}$ using results from outer iterations 1 to $k-1$, not outer iteration $k-1$ only. Hereafter, this expression is refered to as "corrected expression".

3.3 Consitent method

An new alternative method in which the guess consistency is guaranteed can be defined. THis method also have the advantage of requiring much more simpler calculations than the "standard" method and gives the same results. The basic idea is to reverse the order of computations: the first term of the right-hand side is computed first from equation (21), and then the background increment is given by:

$$\delta\mathbf{x}^{b}_{k} = \mathbf{U}_k\delta\mathbf{v}^{b}_{k} \tag{32}$$

Finally, the full resolution guess is deduced as:

$$\mathbf{x}^{g+}_{k} = \mathbf{x}^{b} - \mathbf{T}^{\mathbf{x}}_{k\rightarrow K}\delta\mathbf{x}^{b}_{k} \tag{33}$$

In this method, the guess consistency is maintained since

4 Methodology and results

Show the quadratc cost function (obs and background) + tables

5 Conclusions

TEXT

Code availability. TEXT

Data availability. TEXT

Code and data availability. TEXT

Sample availability. TEXT

Video supplement. TEXT

Appendix A: Equivalence between preconditionners

Another precondi technique consists in defining a new variable $\delta\overline{\mathbf{x}}_k = \mathbf{B}_k^{-1}\delta\mathbf{x}_k$, where $\delta\mathbf{x}_k$ is the state model increment of iteration k of a Gauss-Newton algorithm, and $\mathbf{B_k}$ is the model error covariance matrix, so that the linear system to solve can be written as $\mathbf{A}_k^{\overline{\mathbf{x}}}\delta\overline{\mathbf{x}}_k^a = \mathbf{b}_k^{\overline{\mathbf{x}}}$, $\delta\overline{\mathbf{x}}_k^a$ being the preconditionned analysis increment, and with $\mathbf{A}_k^{\overline{\mathbf{x}}} = \mathbf{I}_n + \mathbf{H}_k^{\mathrm{T}}\mathbf{R}^{-1}\mathbf{H}_k\mathbf{B}_k$ and the right hand side $\mathbf{b}_k^{\overline{\mathbf{x}}} = \delta\overline{\mathbf{x}}_k^b + \mathbf{H}_k^{\mathrm{T}}\mathbf{R}^{-1}\mathbf{d}_k$, where $\mathbf{R}_k$ is the observation error covariance matrix, $\mathbf{H}_k$ is the observation operator linearized around a guess state, and $\mathbf{d_k}$ is the innovation vector **??**.

$$\text{and} \quad \delta\mathbf{v}_k^b = -\sum_{i=1}^{k-1}\delta\mathbf{v}_i^a. \tag{A1}$$

With the full $\mathbf{B}$ preconditioning, $\mathbf{B}^{-1}$ can be applied on both side of equation (7):

$$\boxed{\delta\overline{\mathbf{x}}_k^b = -\sum_{i=1}^{k-1}\delta\overline{\mathbf{x}}_i^a} \tag{A2}$$

With the full $\mathbf{B}$ preconditioning:

$$\begin{aligned}\delta\overline{\mathbf{x}}_k^b &= -\mathbf{B}_k^{-1}\sum_{i=1}^{k-1}\delta\mathbf{x}_i^a \\ &= -\sum_{i=1}^{k-1}\mathbf{B}_k^{-1}\mathbf{B}_i\delta\overline{\mathbf{x}}_i^a \end{aligned}\tag{A3}$$

If $\mathbf{B}_k^{-1}\mathbf{B}_i\delta\overline{\mathbf{x}}_i^a \neq \delta\overline{\mathbf{x}}_i^a$, equation (A2) cannot be used consistently.

$$\delta\overline{\mathbf{x}}_k^b = -\mathbf{B}_k^{-1}\sum_{i=1}^{k-1}\delta\mathbf{x}_i^a = -\sum_{i=1}^{k-1}\mathbf{B}_k^{-1}\mathbf{B}_i\delta\overline{\mathbf{x}}_i^a,\tag{A4}$$

std method:

$$\boxed{\delta\overline{\mathbf{x}}_k^b = -\sum_{i=1}^{k-1}\mathbf{T}^{\mathbf{x}}_{i\to k}\delta\overline{\mathbf{x}}_i^a}\tag{A5}$$

Comparing equations (A5) and (**??**), the guess consistency is maintained if:

$$\begin{aligned}&\mathbf{B}_k^{-1}\mathbf{T}^{\mathbf{x}}_{K\to k}\sum_{i=1}^{k-1}\delta\mathbf{x}_i^{a+} = \sum_{i=1}^{k-1}\mathbf{T}^{\mathbf{x}}_{i\to k}\delta\overline{\mathbf{x}}_i^a \\ \Leftrightarrow\ &\mathbf{T}^{\mathbf{x}}_{K\to k}\sum_{i=1}^{k-1}\delta\mathbf{x}_i^{a+} = \mathbf{B}_k\sum_{i=1}^{k-1}\mathbf{T}^{\mathbf{x}}_{i\to k}\delta\overline{\mathbf{x}}_i^a \\ \Leftrightarrow\ &\boxed{\mathbf{T}^{\mathbf{x}}_{K\to k}\delta\mathbf{x}_{k-1}^{a+} = \mathbf{B}_k\sum_{i=1}^{k-1}\mathbf{T}^{\mathbf{x}}_{i\to k}\delta\overline{\mathbf{x}}_i^a - \mathbf{T}^{\mathbf{x}}_{K\to k}\sum_{i=1}^{k-2}\delta\mathbf{x}_i^{a+}}\end{aligned}\tag{A6}$$

$$\delta\mathbf{x}_1^{a+} = \mathbf{B}_2\mathbf{T}^{\mathbf{x}}_{1\to 2}\delta\overline{\mathbf{x}}_1^a\tag{A7}$$

and

$$\delta\mathbf{x}_{k-1}^{a+} = (\mathbf{T}^{\mathbf{x}}_{K\to k})^{-1}_{\text{right}}\left(\mathbf{B}_k\sum_{i=1}^{k-1}\mathbf{T}^{\mathbf{x}}_{i\to k}\delta\overline{\mathbf{x}}_i^a - \mathbf{T}^{\mathbf{x}}_{K\to k}\sum_{i=1}^{k-2}\delta\mathbf{x}_i^{a+}\right)\tag{A8}$$

and

$$\boxed{\delta\mathbf{x}_{k-1}^{a+} = \mathbf{T}^{\mathbf{x}}_{k\to K}\left(\mathbf{B}_k\sum_{i=1}^{k-1}\mathbf{T}^{\mathbf{x}}_{i\to k}\delta\overline{\mathbf{x}}_i^a - \mathbf{T}^{\mathbf{x}}_{K\to k}\sum_{i=1}^{k-2}\delta\mathbf{x}_i^{a+}\right)}\tag{A9}$$

Similarly in control space:

$$\delta\mathbf{x}^{a+}_{k-1} = \mathbf{T}^{\mathbf{x}}_{k\to K}\mathbf{B}_k\mathbf{T}^{\mathbf{x}}_{k-1\to k}\delta\overline{\mathbf{x}}^{a}_{k-1} + \mathbf{T}^{\mathbf{x}}_{k\to K}\sum_{i=1}^{k-2}\left(\mathbf{B}_k\mathbf{T}^{\mathbf{x}}_{i\to k}\delta\overline{\mathbf{x}}^{a}_{i} - \mathbf{T}^{\mathbf{x}}_{K\to k}\delta\mathbf{x}^{a+}_{i}\right) \tag{A10}$$

If the $\mathbf{B}$ family is projective, then:

$$\mathbf{T}^{\mathbf{x}}_{k\to K}\mathbf{B}_k\mathbf{T}^{\mathbf{x}}_{k-1\to k} = \mathbf{T}^{\mathbf{x}}_{k\to K}\mathbf{T}^{\mathbf{x}}_{k-1\to k}\mathbf{B}_{k-1} = \mathbf{T}^{\mathbf{x}}_{k-1\to K}\mathbf{B}_{k-1} \tag{A11}$$

so a simplified expression of $\delta\mathbf{x}^{a+}_{k-1}$ is:

$$\boxed{\delta\mathbf{x}^{a+}_{k-1} = \mathbf{T}^{\mathbf{x}}_{k-1\to K}\mathbf{B}_{k-1}\delta\overline{\mathbf{x}}^{a}_{k-1}} \tag{A12}$$

that verifies (A9) since both terms inside the summation cancel each other:

$$\begin{aligned}\mathbf{B}_k\mathbf{T}^{\mathbf{x}}_{i\to k}\delta\overline{\mathbf{x}}^{a}_{i} - \mathbf{T}^{\mathbf{x}}_{K\to k}\delta\mathbf{x}^{a+}_{i} &= \mathbf{B}_k\mathbf{T}^{\mathbf{x}}_{i\to k}\delta\overline{\mathbf{x}}^{a}_{i} - \mathbf{T}^{\mathbf{x}}_{K\to k}\mathbf{T}^{\mathbf{x}}_{i\to K}\mathbf{B}_i\delta\overline{\mathbf{x}}^{a}_{i}\\ &= \left(\mathbf{B}_k\mathbf{T}^{\mathbf{x}}_{i\to k} - \mathbf{T}^{\mathbf{x}}_{i\to k}\mathbf{B}_i\right)\delta\overline{\mathbf{x}}^{a}_{i}\\ &= 0\end{aligned} \tag{A13}$$

$$\delta\mathbf{x}^{b}_{k} = \mathbf{B}_k\delta\overline{\mathbf{x}}^{b}_{k} \tag{A14}$$

or

bibou

Author contributions. TEXT

Competing interests. TEXT

Disclaimer. TEXT

Acknowledgements. TEXT

References

REFERENCE 1

REFERENCE 2