

## All-sky approach for the use of SEVIRI WV data

Axel Hutt

Deutscher Wetterdienst, Section FE12: Data Assimilation

# Outlook

**1. Motivation**

**2. Cloud detection**

**3. Next steps**

# Outlook

## 1. Motivation

## 2. Cloud detection

## 3. Next steps

# 1. Motivation

**Aim: assimilation of satellite data to improve weather forecast**

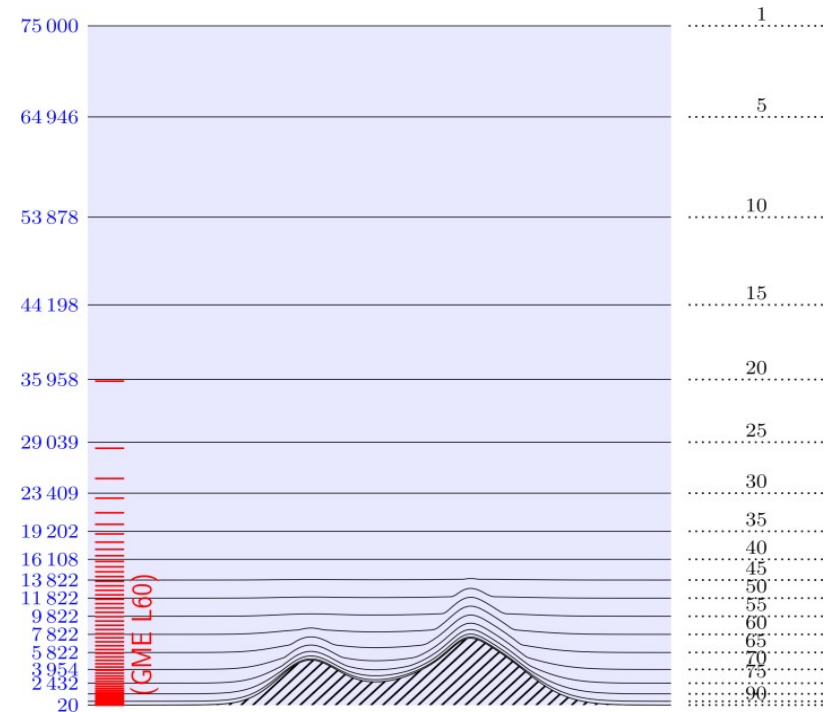
in current *global* ICON-model :

Assimilation of satellite data, e.g. of

- Infrared Atmospheric Sounding Interferometer (IASI):  $3.6\mu\text{m}$ - $15\mu\text{m}$
- Advanced Microwave Sounding Unit (AMSU):  $35\mu\text{m}$ - $150\mu\text{m}$

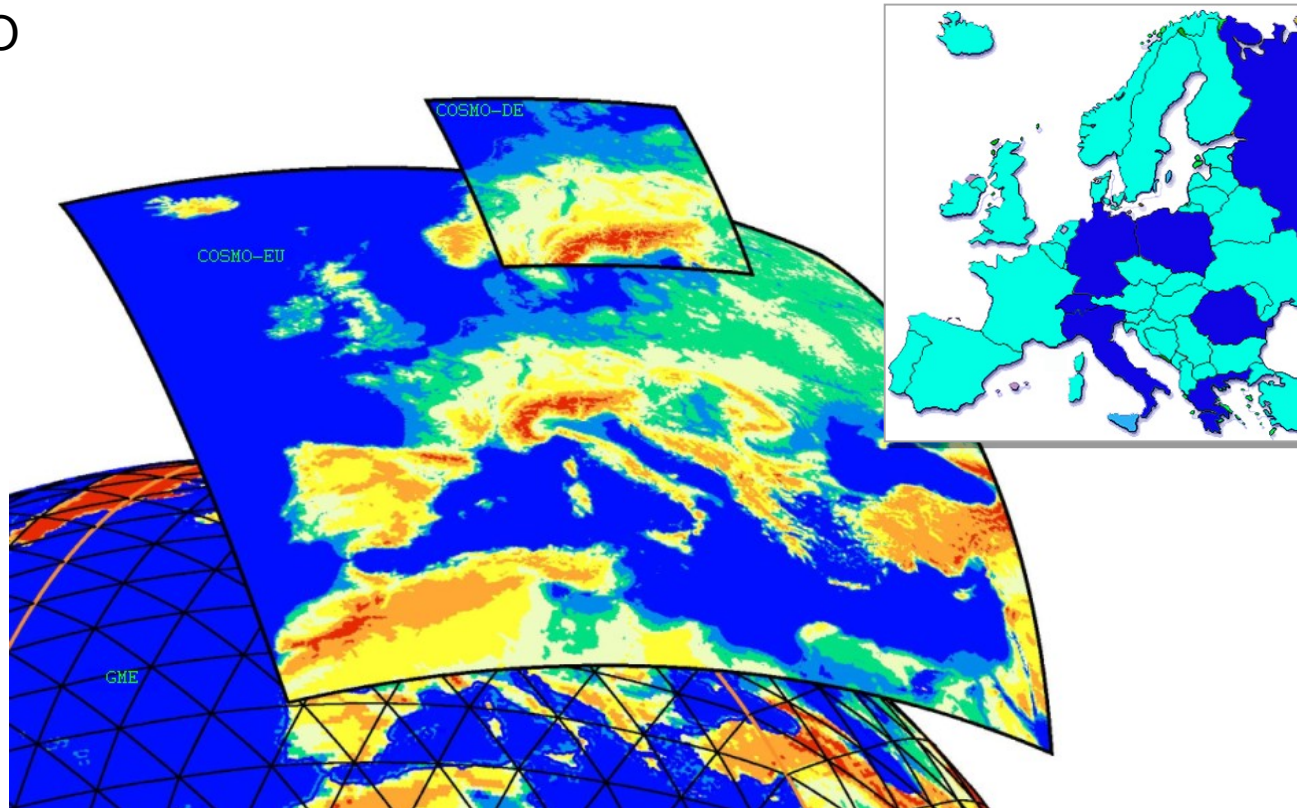
# ICOsahedral Nonhydrostatic (ICON) model

- global model
- horizontal resolution: 13km
- Operational since 2015
- G. Zängl et al.



Images: Florian Prill

# COSMO

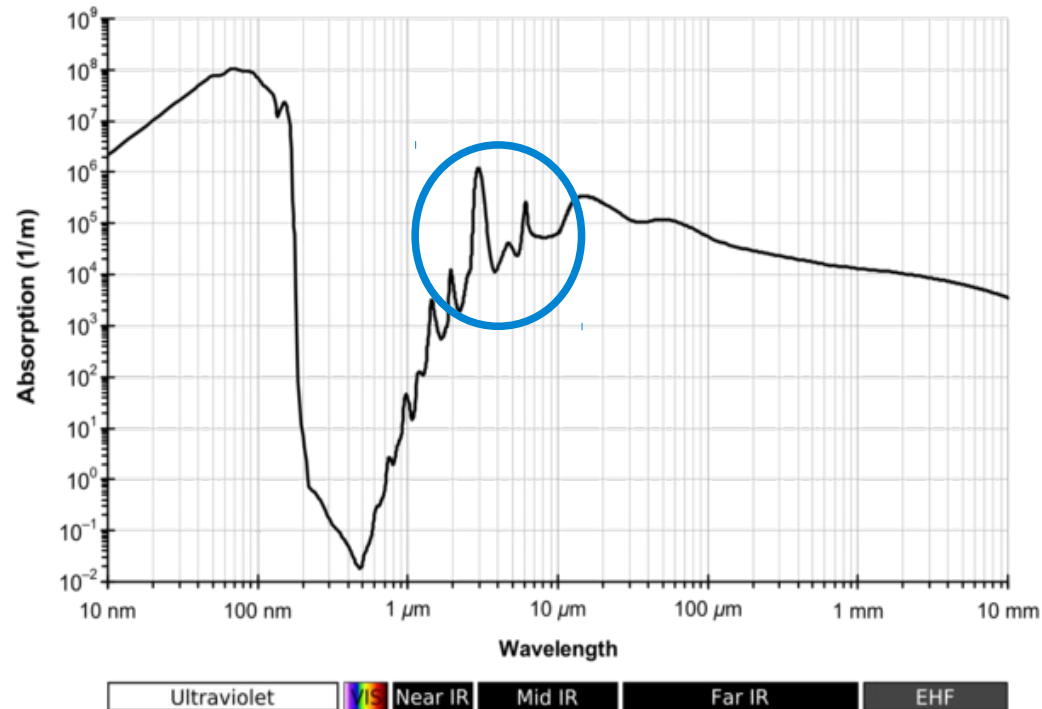


no assimilation of satellite data yet

# 1. Motivation

**Problem: satellite data are affected by clouds**

absorption of infrared radiation by cloud water



# 1. Motivation

in operational *global* ICON-model :

assimilation of satellite data under **clear-sky** conditions:

IASI (3.6 $\mu$ m-15 $\mu$ m) : cloud detection after McNally&Watts (2006)



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in operational *global* ICON-model :

assimilation of satellite data under **clear-sky** conditions:

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im *lokalen* COSMO-Modell :

aim: assimilation of satellite data considering cloud information (**all-sky**)

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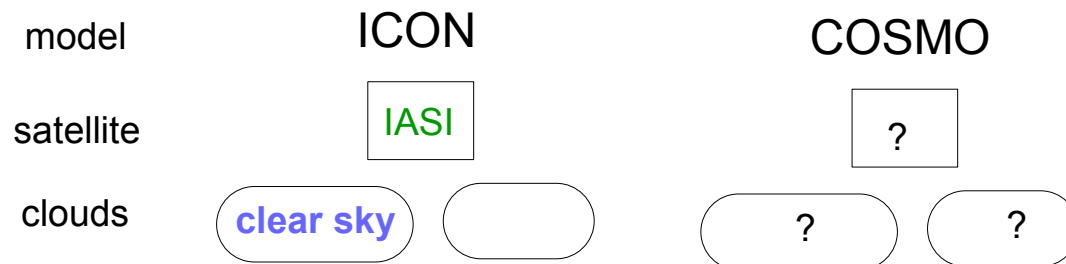
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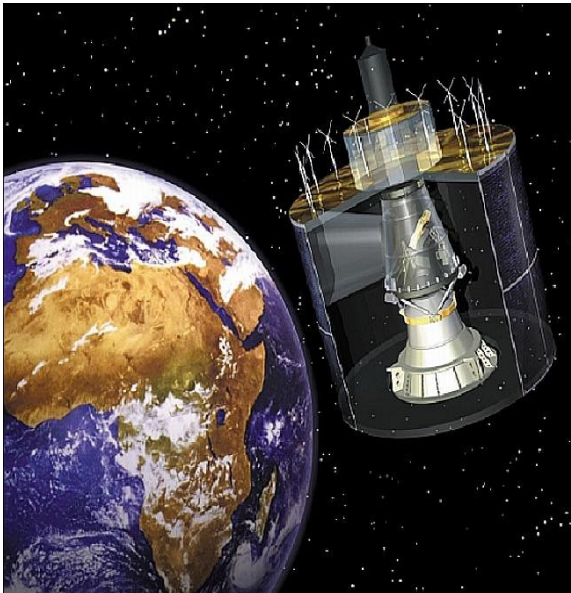
im *lokalen* COSMO-Modell :

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## Choice of satellite instrument:

- Spinning Enhanced Visible and **Infrared** Imager (**SEVIRI**) on MSG3



- geostationary
- 12 spectral channels:
  - 11 channels with 3km resolution
  - 1 visual channel with 1km resolution
  - 8 infrared channels
  - 4 visual/near infrared - channels
- 15 minutes time resolution

# 1. Motivation

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## Assimilation:

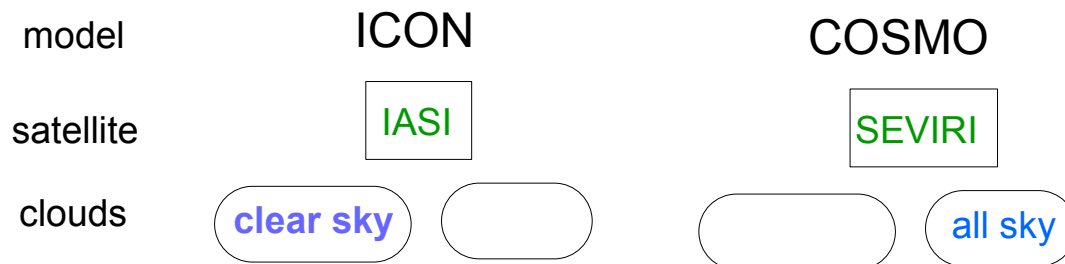
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- Implementation of DA of SEVIRI-data
  - (a) no consideration of cloud information
  - (b) **with consideration of cloud information**

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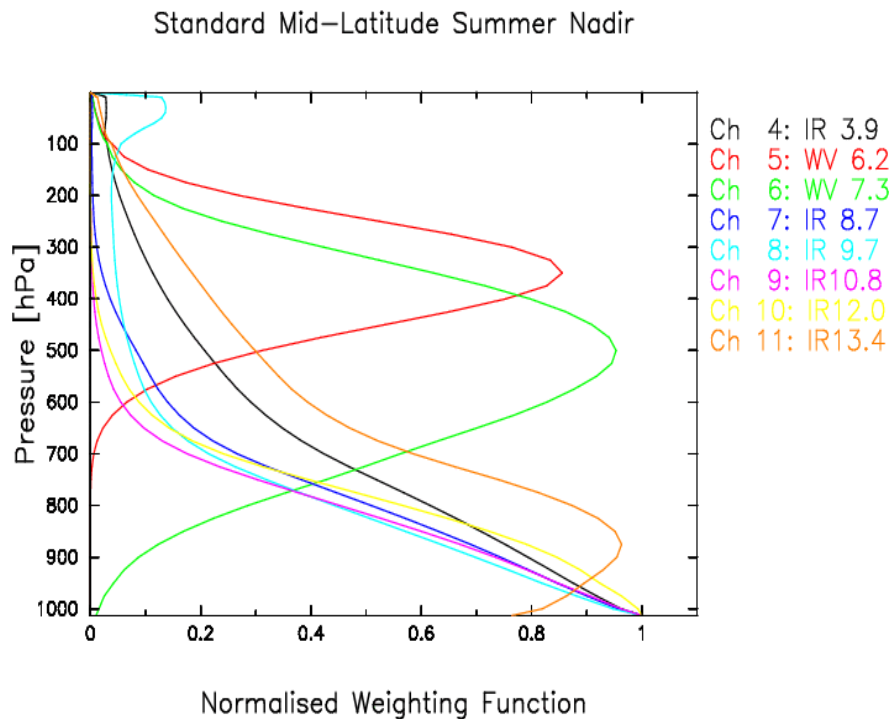
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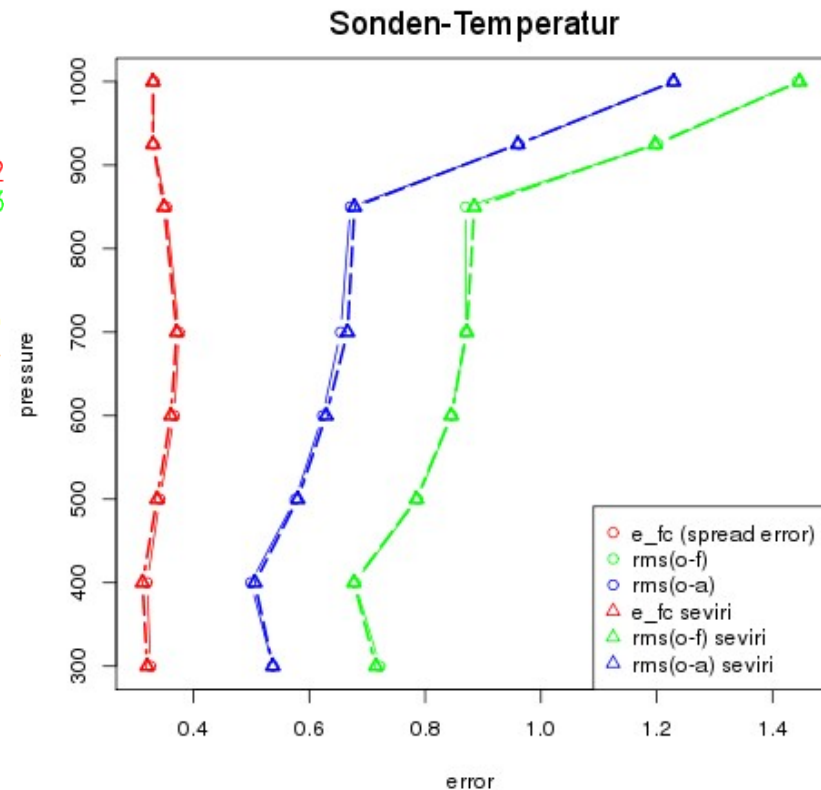
# 1. Motivation

very first result: DA of SEVIRI-Daten without cloud information

## sensitivity of SEVIRI



## DA in water vapour channel 7,3µm



**SEVIRI-DA worse without cloud information**

# Outlook

1. Motivation

**2. Cloud detection**

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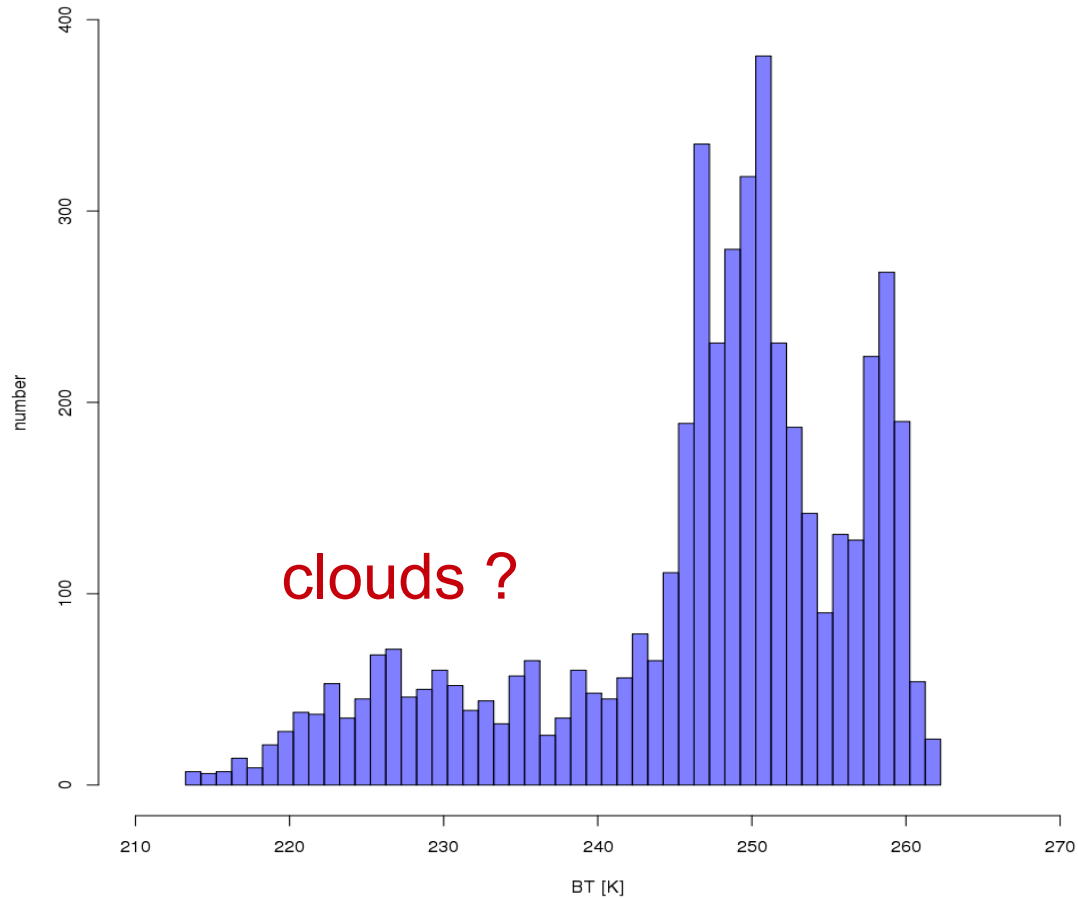


# 2. cloud detection



experimental SEVIRI *brightness temperature* (BT) in channel  $7.3\mu\text{m}$

observations at May 16 2015 , 12 UTC



## 2. cloud detection

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basic question:

cloud detection based on measured data

or

cloud detection based on the model

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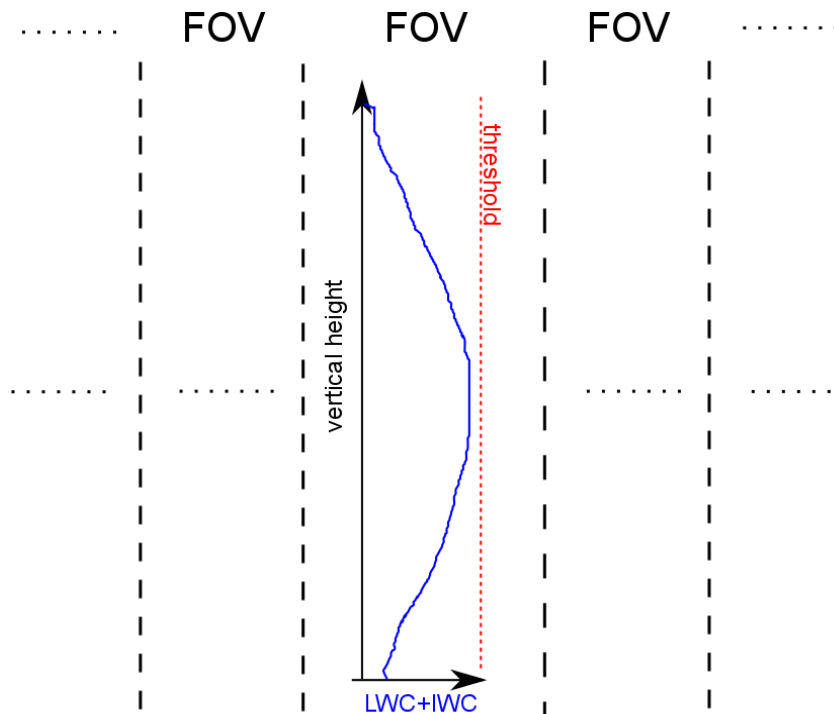
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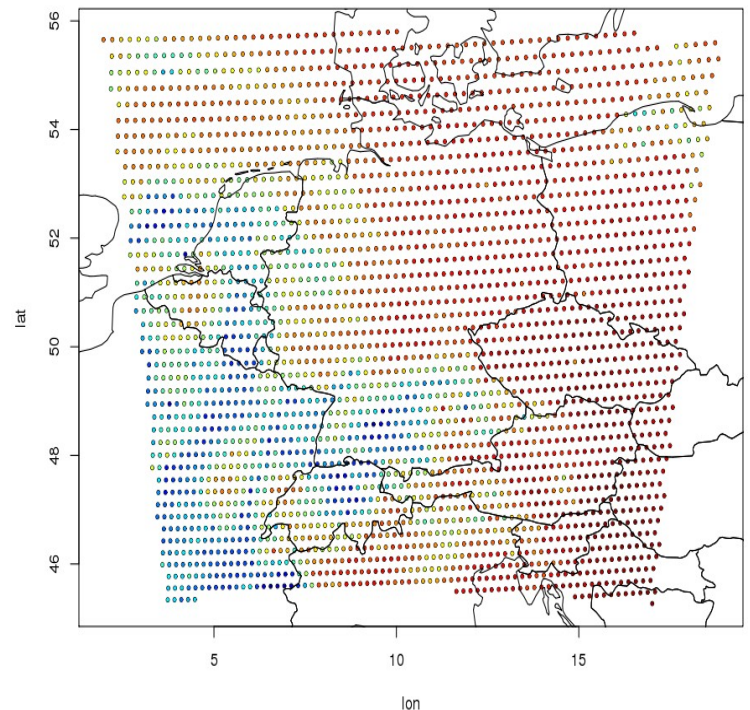
[Harnisch et al., J. R. Meteorol. Soc. \(2016\):](#)

model water content in atmosphere defines cloud existence

liquid and ice water content in COSMO-model



spatial segmentation in clear/cloudy areas



## 2. cloud detection

If  $LWC+IWC > \theta$  at spatial location:

model first guess and observation BT are affected by clouds

If  $LWC+IWC \leq \theta$  at spatial location:

model first guess and observation BT are clear

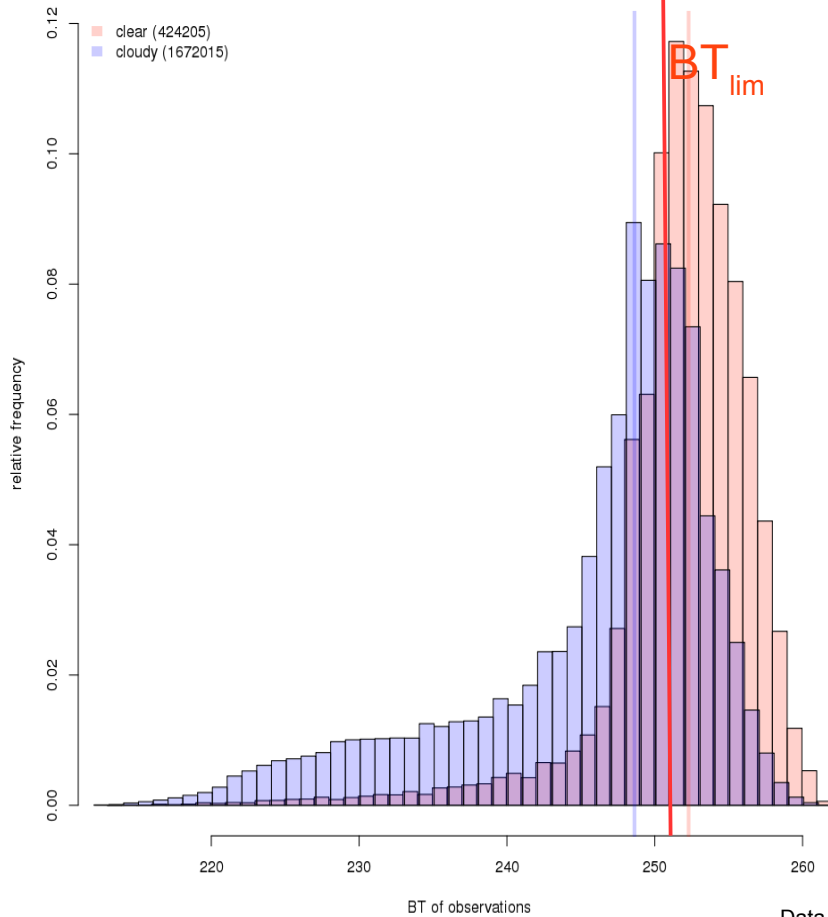


segmentation of Field Of Views (FOV) into clear and cloudy

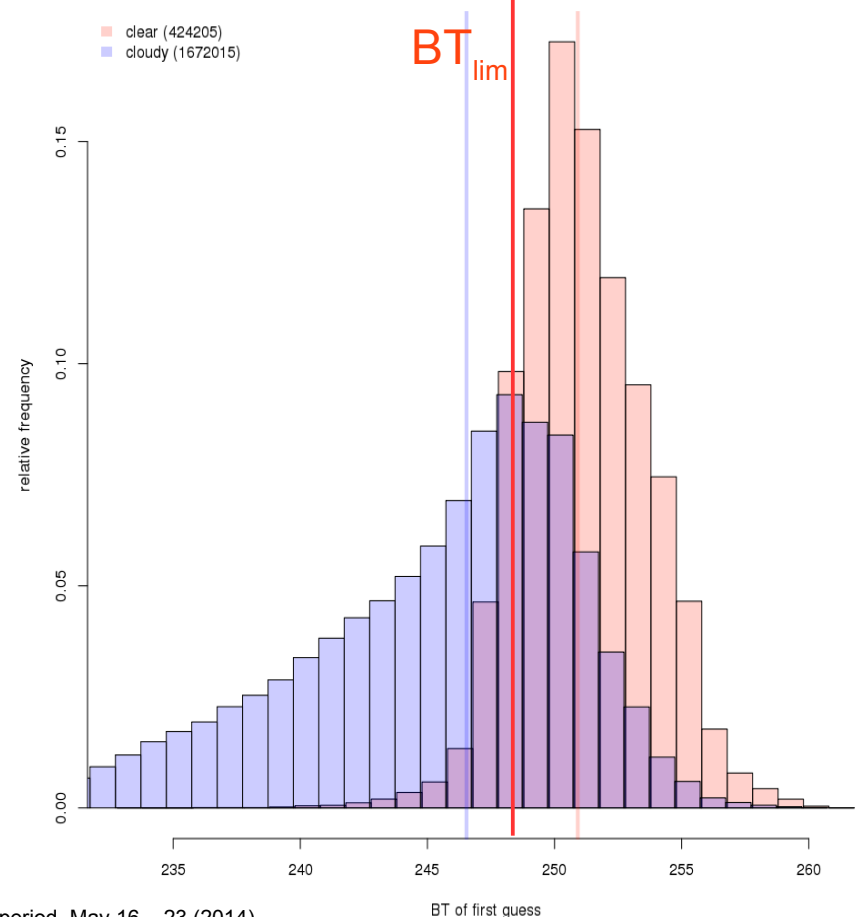
# 2. cloud detection



distribution of observations , threshold=0.001



distribution of first guess , threshold=0.001



Data from time period May 16 – 23 (2014)

brightness temperature  $Bt_{lim}$  separates clear and cloudy BT

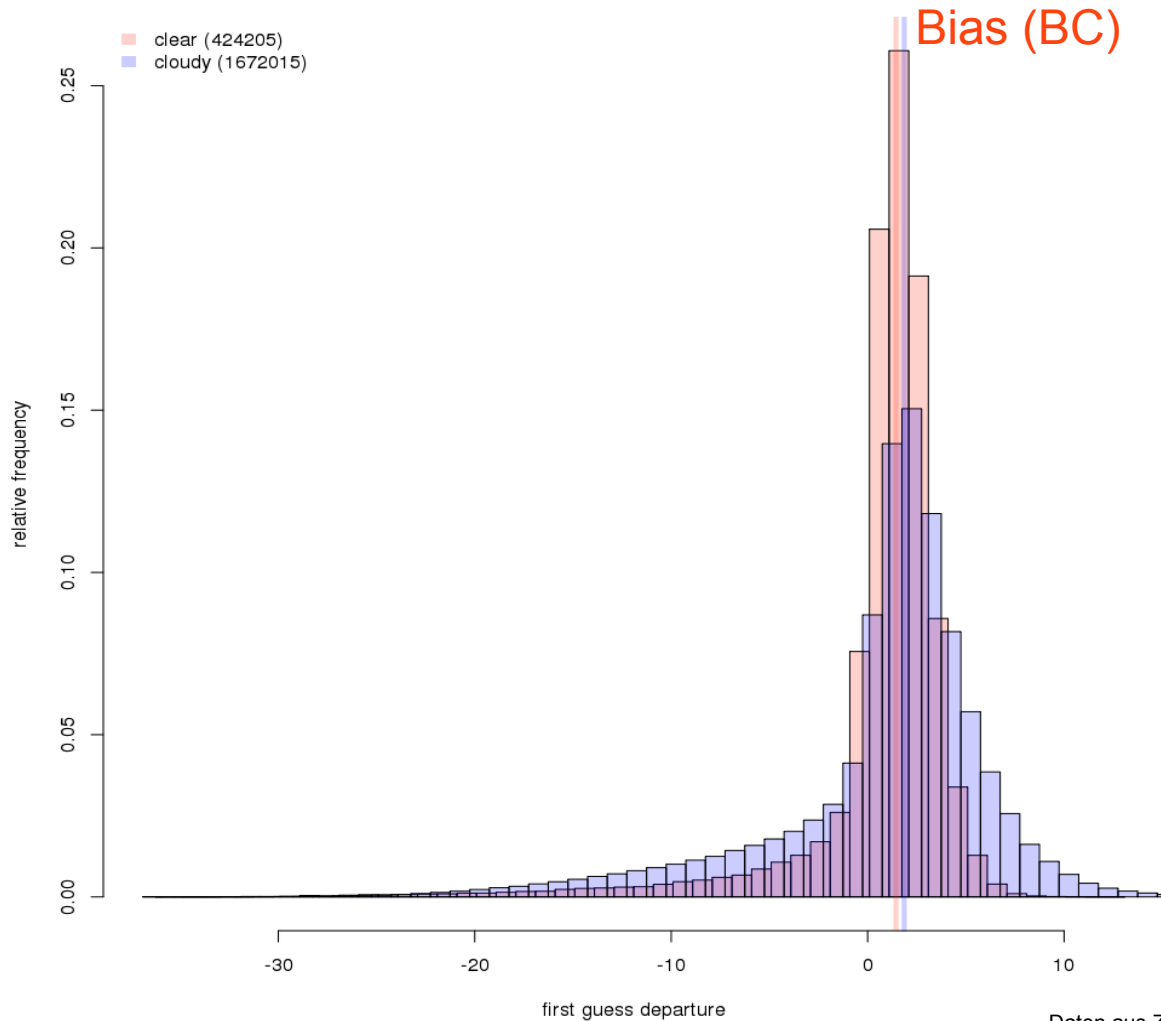




# 2. cloud detection



distribution of first guess departures , threshold=0.001



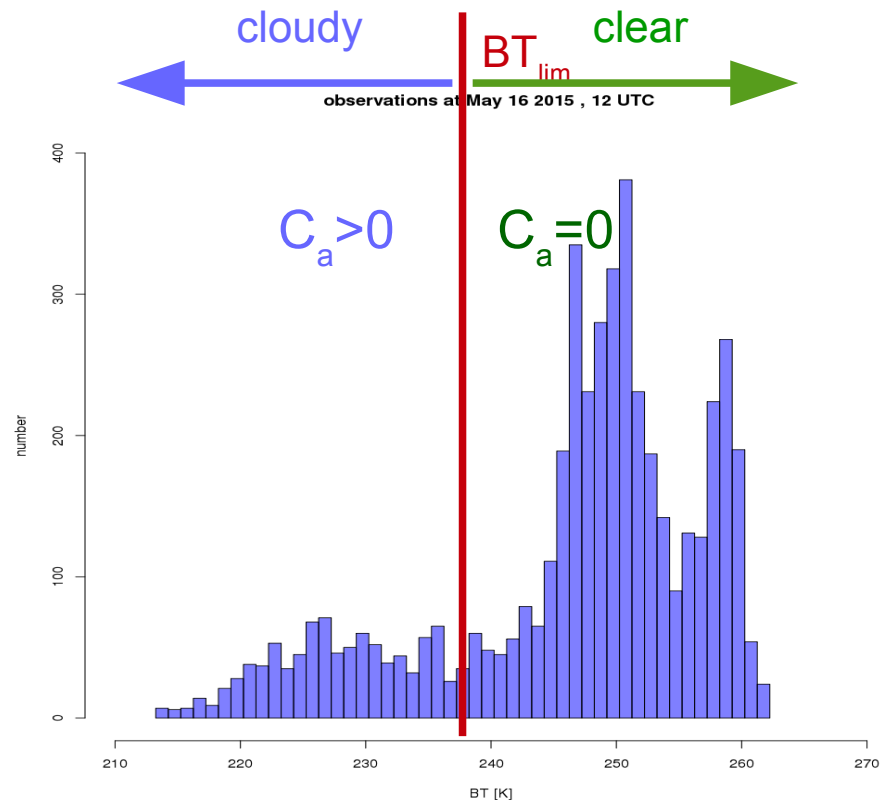
Daten aus Zeitraum 16-23 Mai 2014



# 2. cloud detection

impact of clouds on brightness temperature:

- average cloud impact  $C_a$  [K]
- average of cloud impact on observations and model first guess



# 2. cloud detection

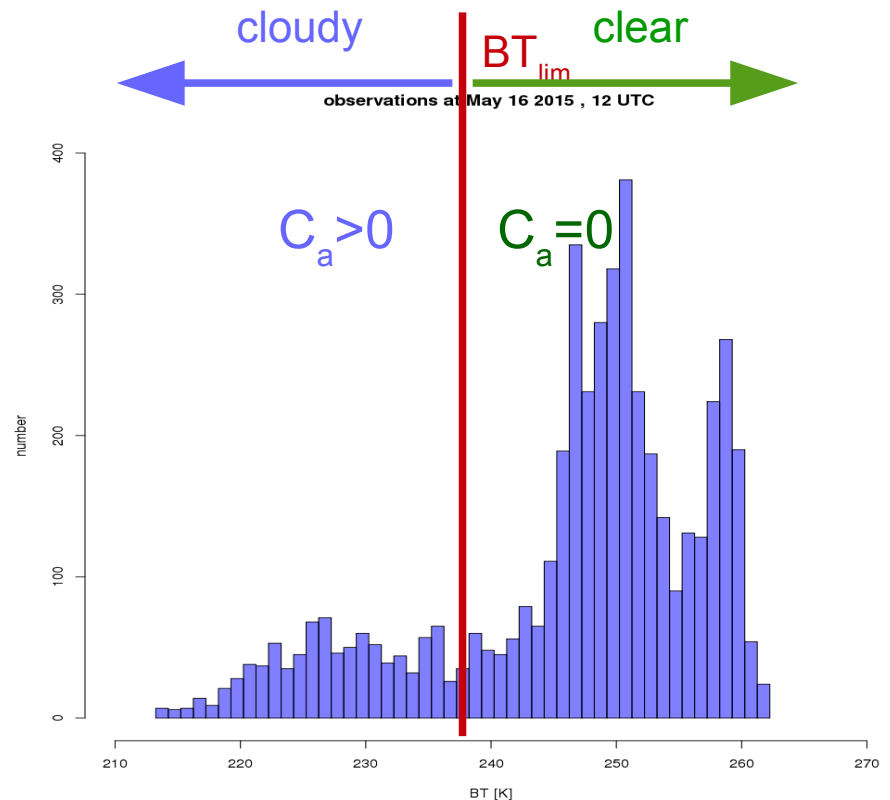


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Cloud impact on first guess:

$$C_{fg} = \max(0, BT_{lim} - BT)$$



# 2. cloud detection



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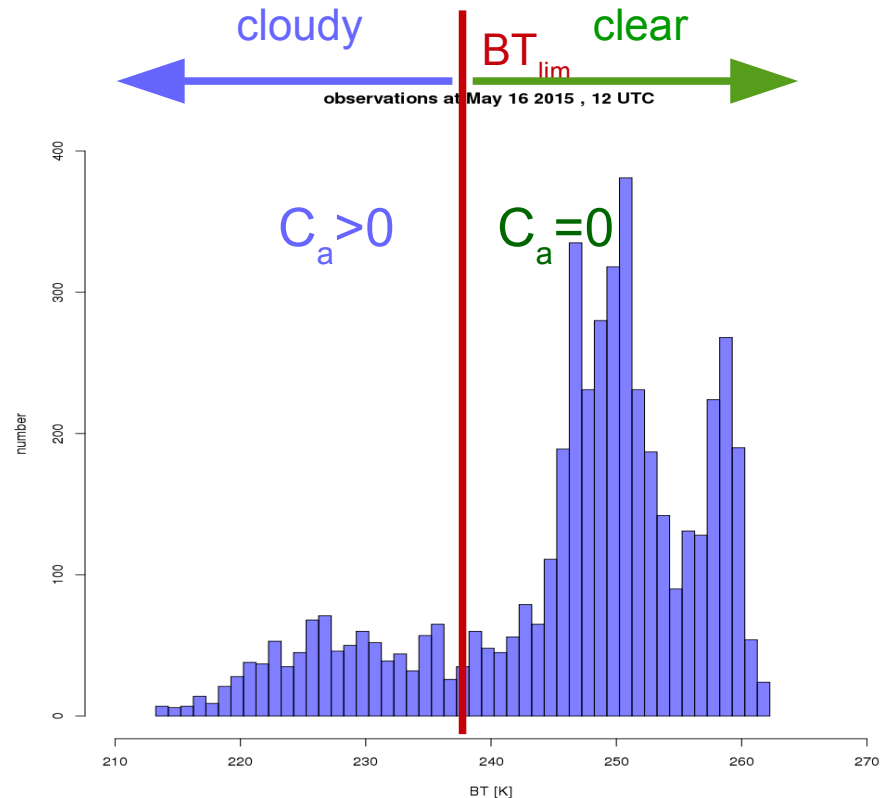
- average cloud impact  $C_a$  [K]
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Cloud impact on first guess:

$$C_{fg} = \max(0, BT_{lim} - BT)$$

Cloud impact on observations:

$$C_{obs} = \max(0, BT_{lim} - (BT - BC))$$



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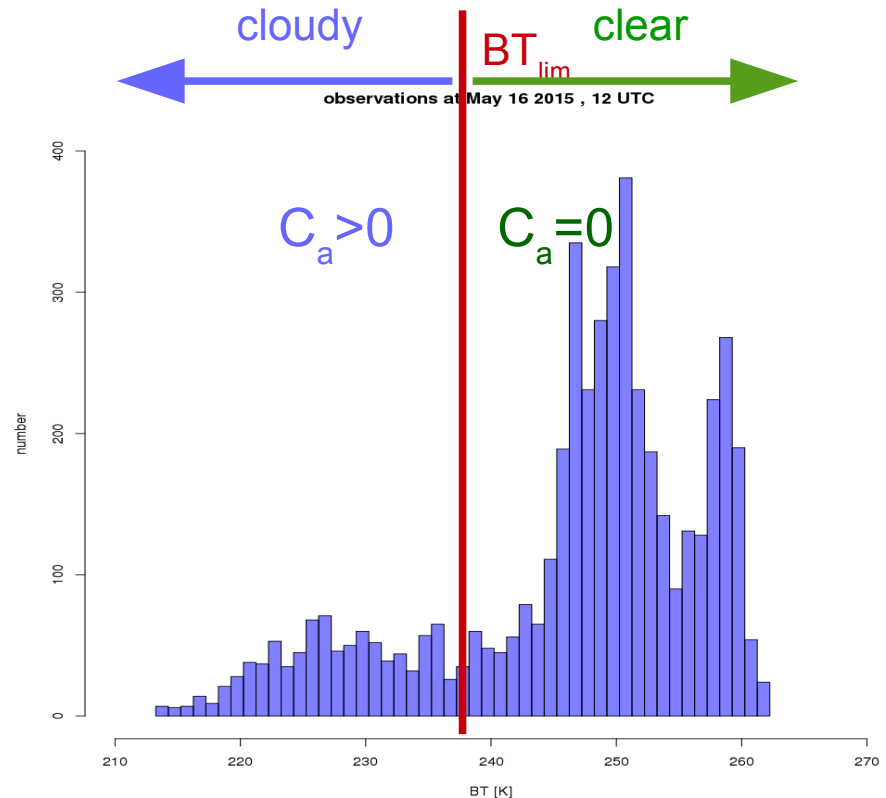
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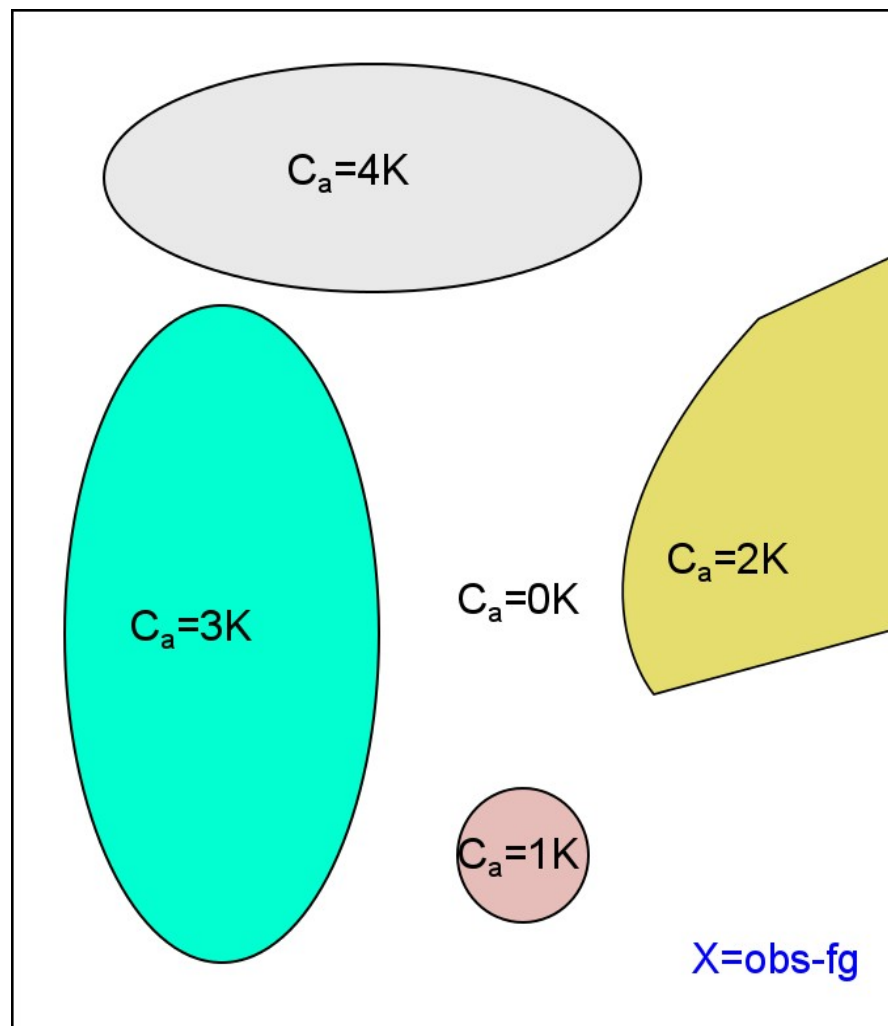
average cloud impact :

$$C_a = (C_{fg} + C_{obs}) / 2$$



## 2. cloud detection

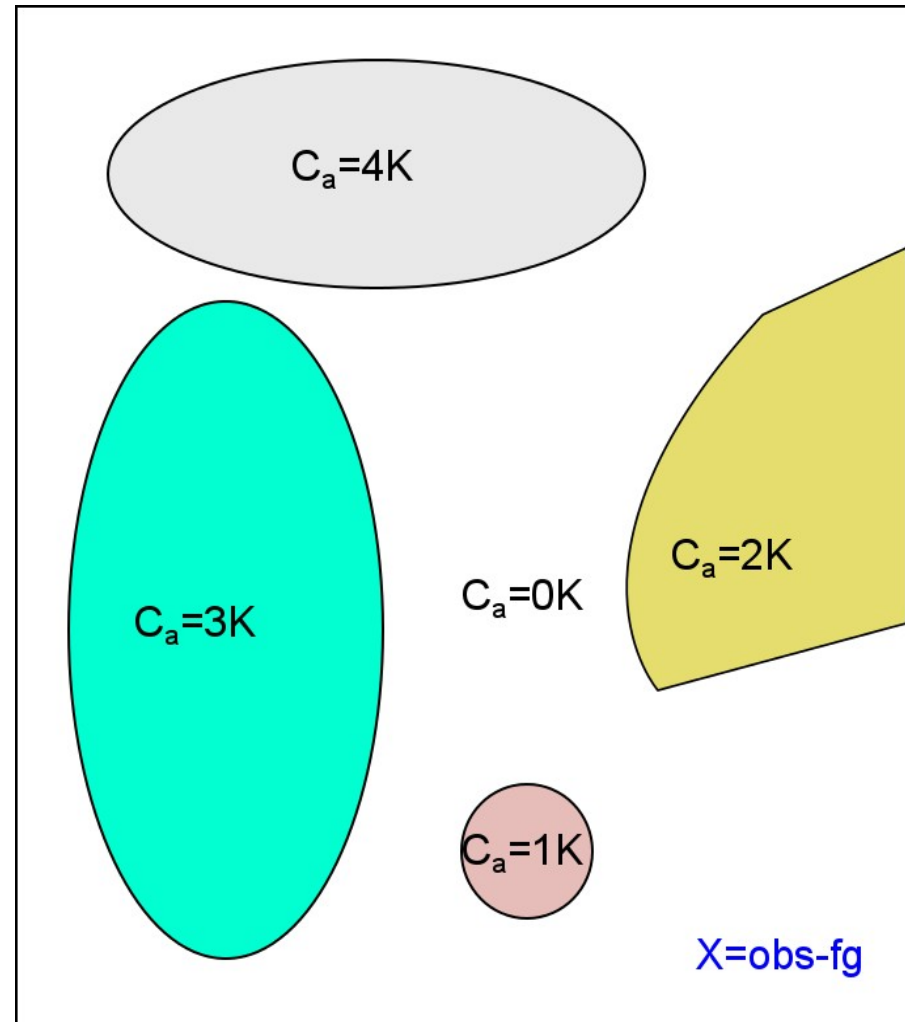
One maps one value of  $C_a$   
to each FOV



## 2. cloud detection

One maps one value of  $C_a$   
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binning all  $C_a$  values:  
consider set of  $X$ =obs-first guess  
for each  $C_a$



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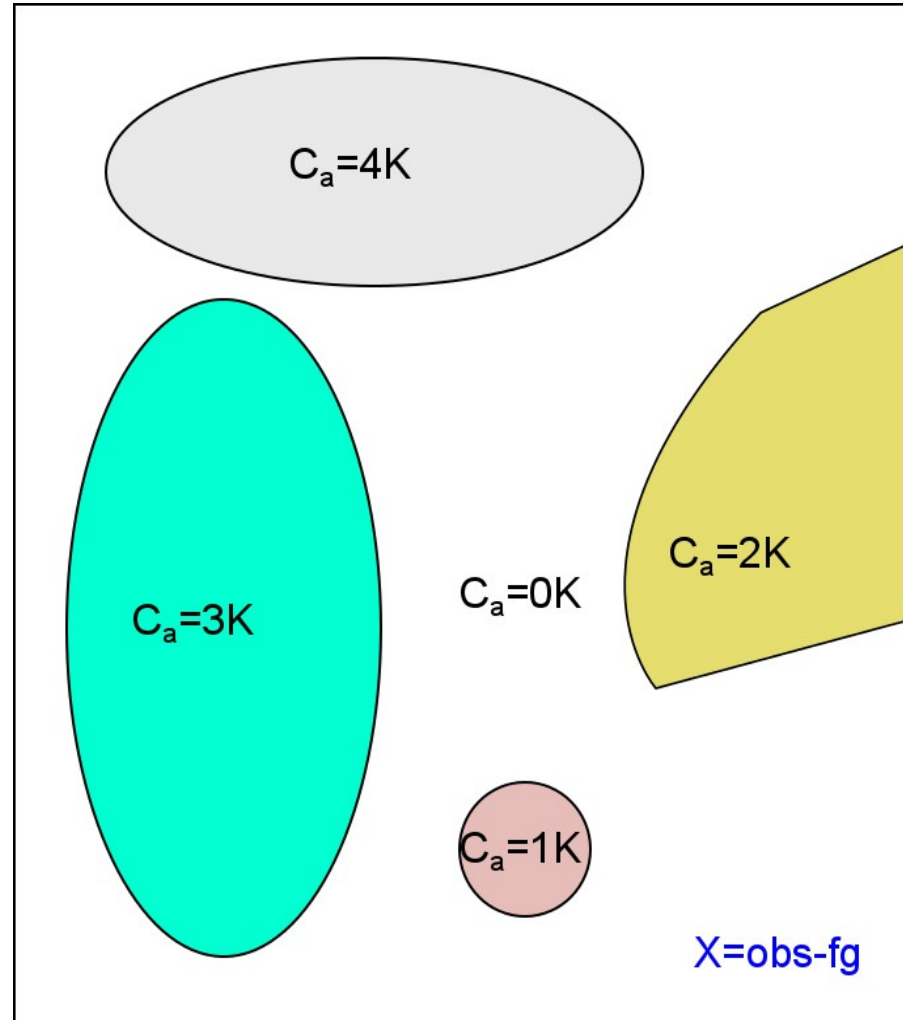


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mean of  $\{X\}$ : bias

variance of  $\{X\}$ :  $\sigma^2 = \sigma_{\text{fg}}^2 + \sigma_{\text{obs}}^2$   
observation error





# 2. cloud detection



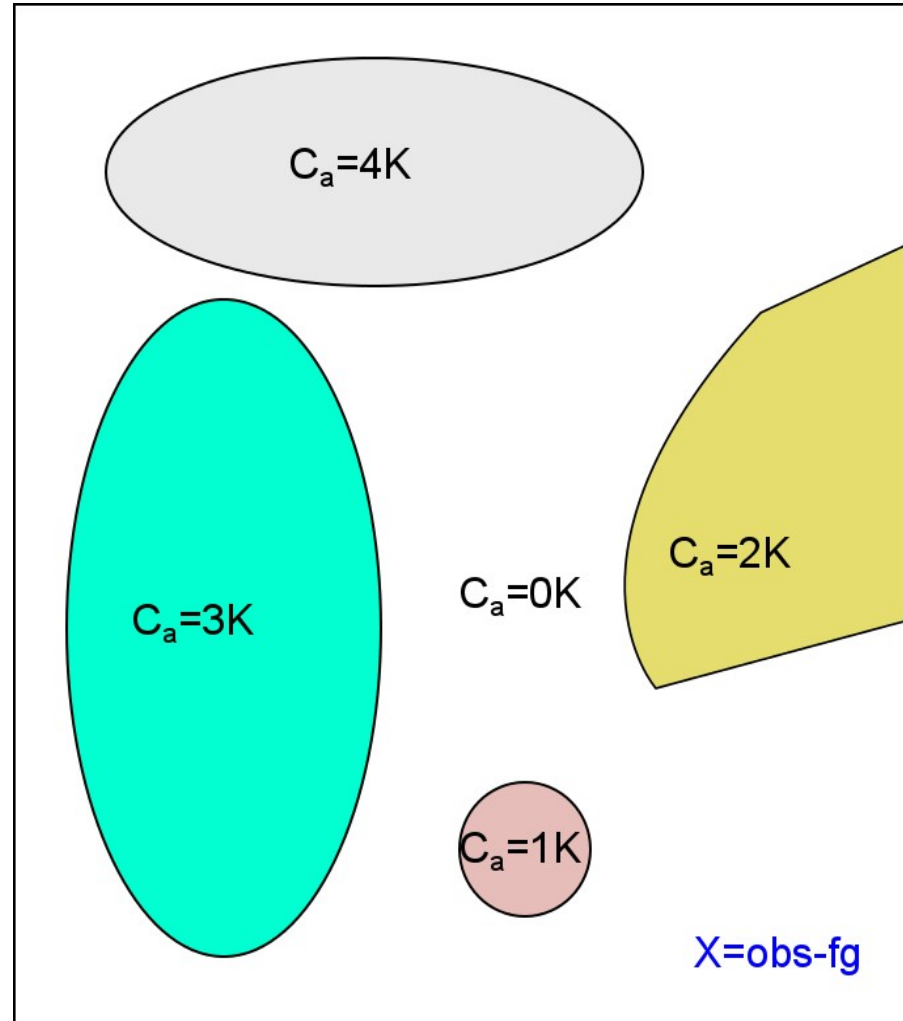
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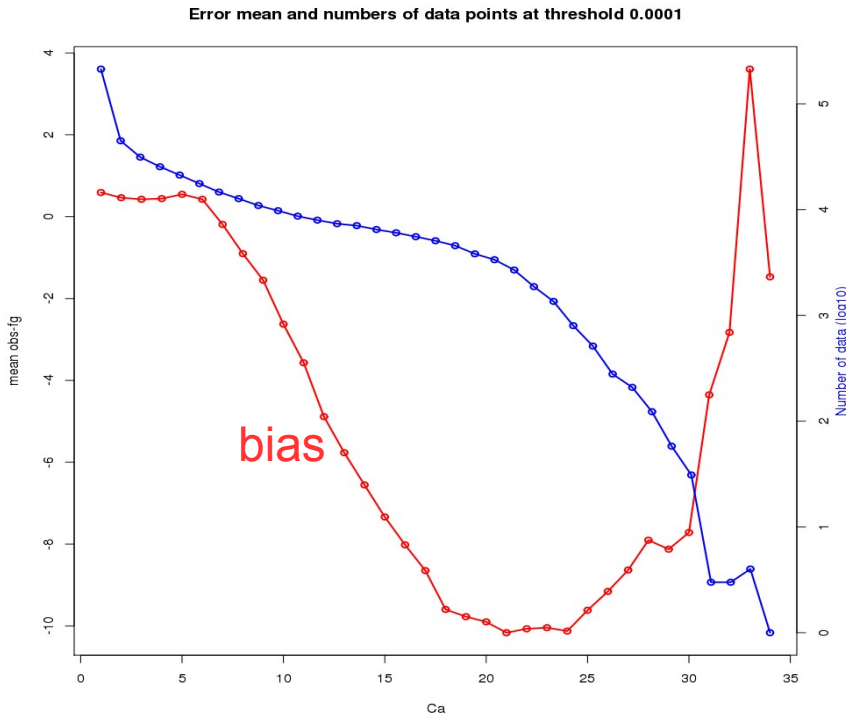
$Y = X / \sigma(C_a)$  : normal distributed ?



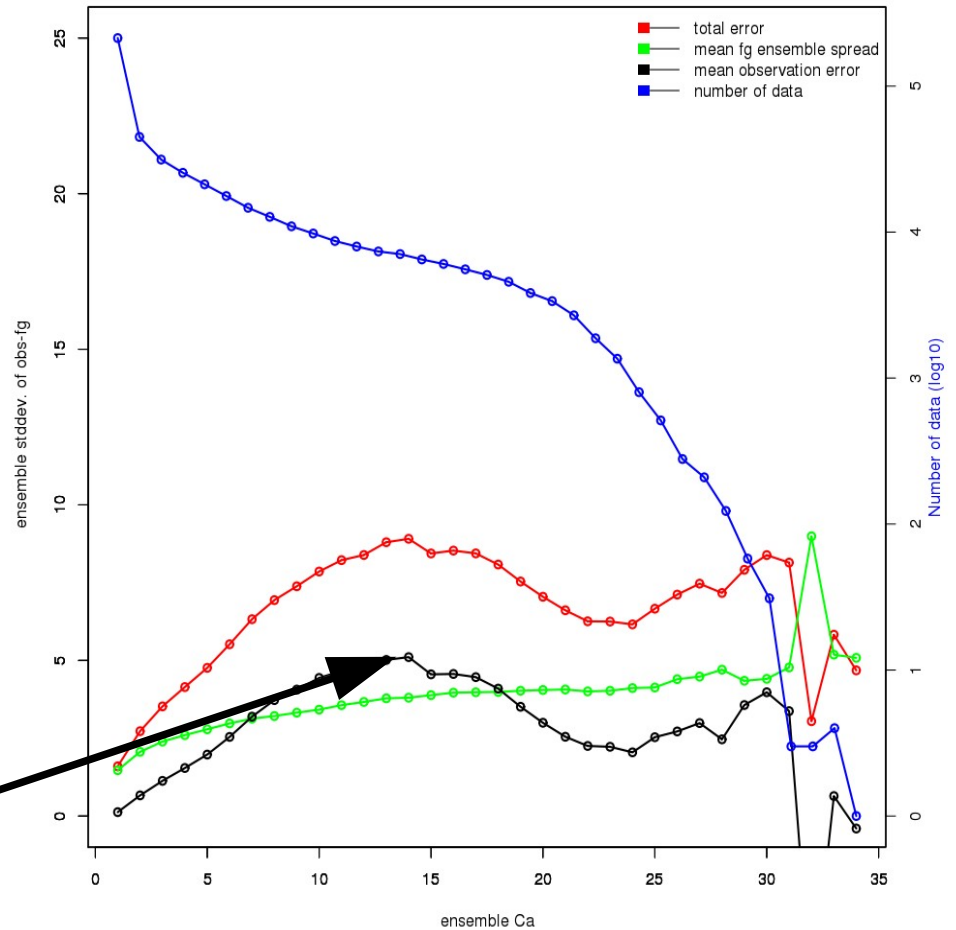
# 2. cloud detection



Error ensemble standard deviation and numbers of data points at threshold 0.0001



new observation error



Data from time period May 16-23 (2014)

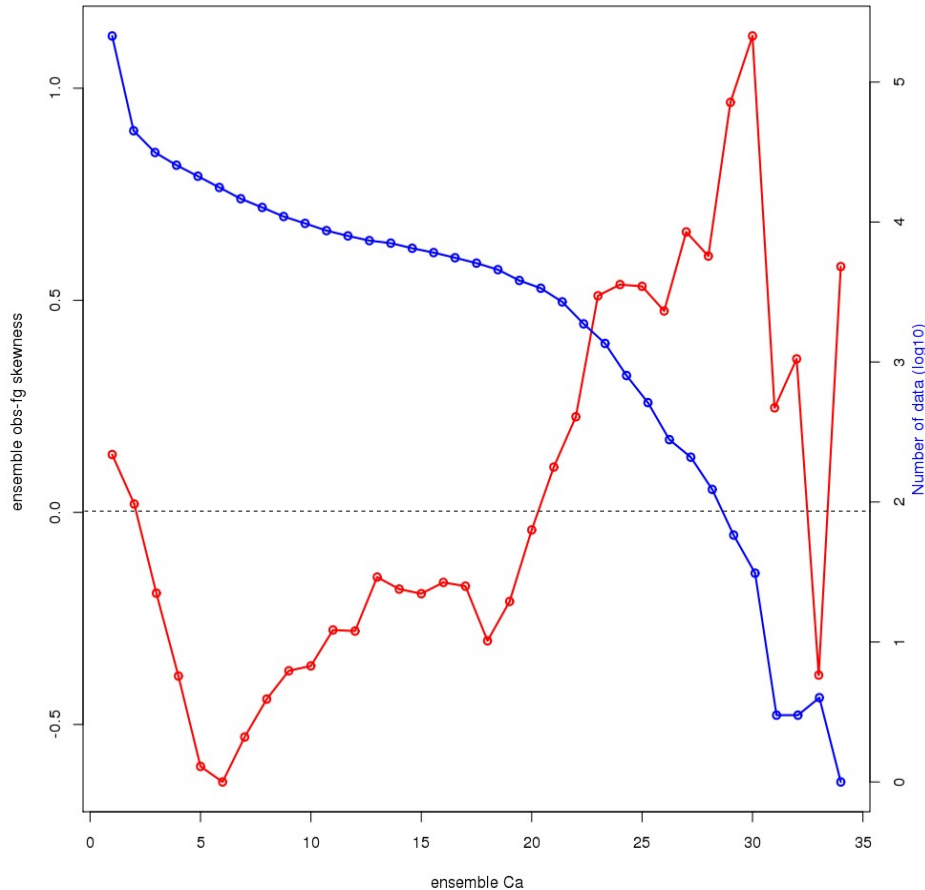


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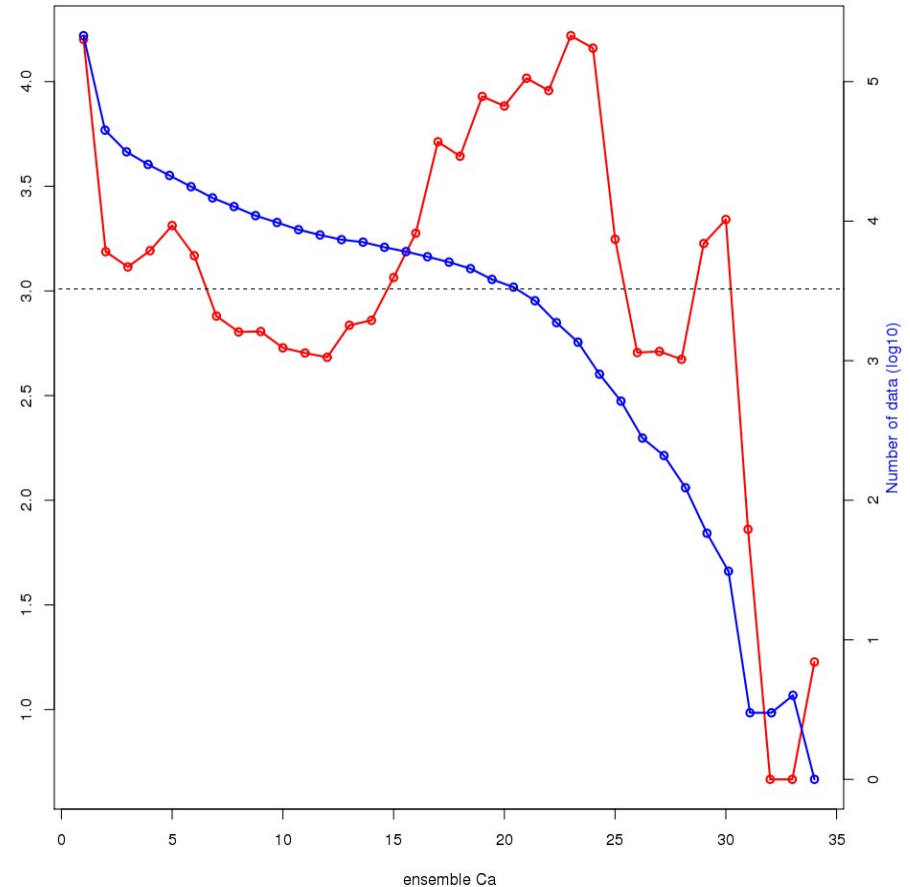
## skewness

Error ensemble skewness and numbers of data points at threshold 0.0001



## kurtosis

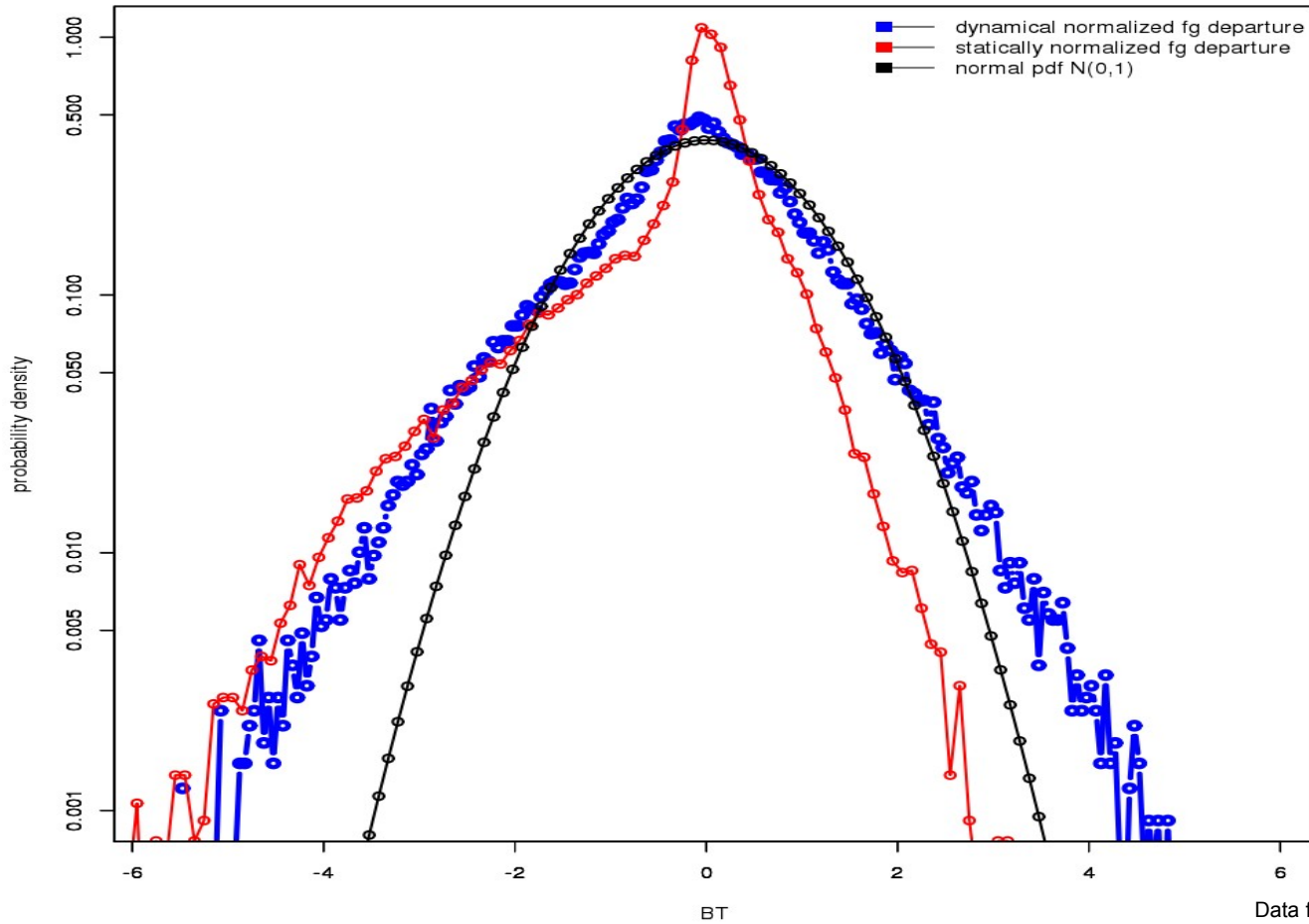
Error ensemble kurtosis and numbers of data points at threshold 0.0001



# 2. cloud detection



probability density functions of ensemble fg departure at threshold 0.0001



**cloud-dependent classification of BT improves statistics**



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# 3. next steps

- Implementation of new observation error in KENDA

—————▶ improvement of forecast ?

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- Improvement of cloud analysis in COSMO:
  - × cloud fraction
  - × precipitation



# 3. next steps

- Implementation of new observation error in KENDA

—————▶ improvement of forecast ?

- Improvement of cloud analysis in COSMO:
  - × cloud fraction
  - × precipitation
- comparison to cloud analysis based on observations, e.g.
  - × Nowcasting SAF product (Schomburg et al. (2015))

Collaboration partners:

- R. Faulwetter, C. Schraff, H. Reich, A. Rhodin, H. Anlauf, R. Potthast  
(German Meteorological Service, Offenbach)
- Jason Otkin (University of Wisconsin-Madison)

Thank you for your attention