



# *A Novel Data Assimilation Model for the Plasmasphere*

***CEDAR Workshop 2017***

***AGS-PRF: No AGS-1231207***

***R. Nikoukar***

*The Johns Hopkins University Applied Physics Laboratory*

***Mentors: G. Bust<sup>1</sup>, and D. Murr<sup>2</sup>***

*<sup>1</sup>The Johns Hopkins University Applied Physics Laboratory*

*<sup>2</sup>Augsburg College*



**JOHNS HOPKINS**  
APPLIED PHYSICS LABORATORY

# Objective and Motivation

## ▪ Objective:

- Apply the idea of data assimilation to the plasmasphere
- To develop a plasmaspheric data assimilation technique to produce time-evolving maps of plasmasphere density 3D structures.

## ▪ Motivation

- Data assimilation is a mathematical framework for the statistical union between observations and empirical or physics-based models.
- It allows for ingestion of various types of geospace measurements.

# Methodology – Data Assimilation

- **Inspired by Ionosphere Data Assimilation 4D (IDA4D) [Bust et al. 2004]**

- **Model:**

- Global Core Plasma (GCP) Model [Gallagher et al., 2000]:
- Empirical, Kp driven

- **Data:**

- COSMIC Satellites: Total electron content (TEC) from precise orbit determination
  - Utilize upward looking GPS TEC signals

- **Forward model:**

- Relating observations to state variables (electron density)
  - Line-of-sight integration

$$TEC = \int N_e(z) dz + \varepsilon_k \quad \text{or} \quad y_k = H_k x_k + \varepsilon_k$$

- **Inverse model:**

- Define an objective function: least squares solution

$$x_k^a = \arg \min \frac{1}{2} \left( \|y_k - H_k x_k\|_{R_k^{-1}}^2 \right)$$

- H is ill-conditioned, in general. Cannot solve directly via  $x_k = H^{-1}y_k$

# Methodology – Data Assimilation

- Inspired by Ionosphere Data Assimilation 4D (IDA4D) [Bust et al. 2004]

- **Model:**

- Global Core Plasma (GCP) Model [Gallagher et al., 2000]:
- Empirical, Kp driven

- **Data:**

- COSMIC Satellites: Total electron content (TEC) from precise orbit determination
  - Utilize upward looking GPS TEC signals

- **Forward model:**

- Relating observations to state variables (electron density)
- Line-of-sight integration

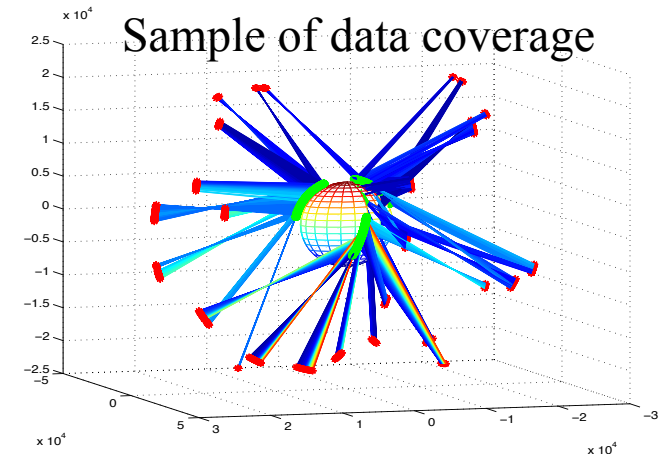
$$TEC = \int N_e(z) dz + \varepsilon_k \quad \text{or} \quad y_k = H_l$$

- **Inverse model:**

- Define an objective function: least sq

$$x_k^a = \arg \min \frac{1}{2} (\|y_k - l\|)$$

- H is ill-conditioned, in general. Canc



# Methodology – Data Assimilation

- **A Priori constraint: add the background model – 3D-VAR**
  - Objective function combining the deviation from the data and the model
  - **3D-VAR: estimate 3D structure of the unknown state**

$$\mathbf{x}_k^a = \arg \min_{\mathbf{x}_k} \frac{1}{2} \left( \|\mathbf{y}_k - \mathbf{H}_k \mathbf{x}_k\|_{R_k^{-1}}^2 + \|\mathbf{x}_k - \mathbf{x}_k^b\|_{P_b^{-1}}^2 \right)$$

- Where  $R_k^{-1}$  and  $P_b^{-1}$  are the data error covariance and model error covariance, respectively.
- Analytical expressions exist:

$$\begin{aligned} \mathbf{x}_k^a &= \mathbf{x}_k^b + \mathbf{P}_k^b \mathbf{H}_k^T [\mathbf{R}_k + \mathbf{H}_k \mathbf{P}_k^b \mathbf{H}_k^T]^{-1} (\mathbf{y}_k - \mathbf{H}_k \mathbf{x}_k^b) \\ \mathbf{P}_k^a &= \mathbf{P}_k^b - \mathbf{P}_k^a \mathbf{H}_k^T [\mathbf{R}_k + \mathbf{H}_k \mathbf{P}_k^b \mathbf{H}_k^T]^{-1} \mathbf{H}_k \mathbf{P}_k^b \end{aligned}$$

# Methodology – Data Assimilation

- **A Priori constraint: add the background model – 3D-VAR**
  - Objective function combining the deviation from the data and the model
  - 3D-VAR: estimate 3D structure of the unknown state

$$x_k^a = \arg \min_{x_k} \frac{1}{2} \left( \|y_k - H_k x_k\|_{R_k^{-1}}^2 + \|x_k - x_k^b\|_{P_b^{-1}}^2 \right)$$

- Where  $R_k^{-1}$  and  $P_b^{-1}$  are the data error covariance and model error covariance, respectively.

- We find that with the ingestion of upward looking data alone, the problem remains ill-posed.
- Hence, we further constrain the solution to be vertically smooth.

$$x_k^{aMAP} = \arg \min_{x_k} \frac{1}{2} \left( \|y_k - H_k x_k\|_{R_k^{-1}}^2 + \|x_k - x_k^b\|_{P_b^{-1}}^2 + \lambda^2 \|D(x_k - x_k^b)\|^2 \right)$$

- Where  $D$  and  $\lambda$  are the regularization functional and regularization parameter, respectively.

# Methodology – Data Assimilation

- **A Priori constraint: add the background model – 3D-VAR**
  - Objective function combining the deviation from the data and the model
  - 3D-VAR: estimate 3D structure of the unknown state

$$x_k^a = \arg \min_{x_k} \frac{1}{2} \left( \|y_k - H_k x_k\|_{R_k^{-1}}^2 + \|x_k - x_k^b\|_{P_b^{-1}}^2 \right)$$

- Where  $R_k^{-1}$  and  $P_b^{-1}$  are the data error covariance and model error covariance, respectively.

- We find that with the ingestion of upward looking data alone, the problem remains ill-posed.
- Hence, we further constrain the solution to be vertically smooth.

$$x_k^{aMAP} = \arg \min_{x_k} \frac{1}{2} \left( \|y_k - H_k x_k\|_{R_k^{-1}}^2 + \|x_k - x_k^b\|_{P_b^{-1}}^2 + \lambda^2 \|D(x_k - x_k^b)\|^2 \right)$$

Where  $D$  and  $\lambda$  are the regularization functional and regularization parameter, respectively.

$$x_k^{aMAP} = \arg \min_{x_k} \frac{1}{2} \left( \lambda^2 \|D(x_k - x_k^b)\|^2 + \|x_k - x_k^a\|_{P_a^{-1}}^2 + C \right)$$

# Methodology – Data Assimilation

- **A Priori constraint: add the background model – 3D-VAR**
  - Objective function combining the deviation from the data and the model
  - 3D-VAR: estimate 3D structure of the unknown state

$$x_k^a = \arg \min_{x_k} \frac{1}{2} \left( \|y_k - H_k x_k\|_{R_k^{-1}}^2 + \|x_k - x_k^b\|_{P_b^{-1}}^2 \right)$$

- Where  $R_k^{-1}$  and  $P_b^{-1}$  are the data error covariance and model error covariance, respectively.

- We find that with the ingestion of upward looking data alone, the problem remains ill-posed.
- Hence, we further constrain the solution to be vertically smooth.

$$x_k^{aMAP} = \arg \min_{x_k} \frac{1}{2} \left( \|y_k - H_k x_k\|_{R_k^{-1}}^2 + \|x_k - x_k^b\|_{P_b^{-1}}^2 + \lambda^2 \|D(x_k - x_k^b)\|^2 \right)$$

Where  $D$  and  $\lambda$  are the regularization functional and regularization parameter, respectively.

$$x_k^{aMAP} = \arg \min_{x_k} \frac{1}{2} \left( \lambda^2 \|D(x_k - x_k^b)\|^2 + \|x_k - x_k^a\|_{P_a^{-1}}^2 + C \right)$$

$$x_k^{aMAP} = x_k^a + P_k^a D^T [I + D P_k^a D^T]^{-1} (x_k^b - D x_k^a)$$



# Methodology – Data Assimilation

- **A Priori constraint: add the background model – 3D-VAR**
  - Objective function combining the deviation from the data and the model
  - 3D-VAR: estimate 3D structure of the unknown state

$$x_k^a = \arg \min_{x_k} \frac{1}{2} \left( \|y_k - H_k x_k\|_{R_k^{-1}}^2 + \|x_k - x_k^b\|_{P_b^{-1}}^2 \right)$$

- Where  $R_k^{-1}$  and  $P_b^{-1}$  are the data error covariance and model error covariance, respectively.

- We find that with the ingestion of upward looking data alone, the problem remains ill-posed.
- Hence, we further constrain the solution to be vertically smooth.

$$x_k^{aMAP} = \arg \min_{x_k} \frac{1}{2} \left( \|y_k - H_k x_k\|_{R_k^{-1}}^2 + \|x_k - x_k^b\|_{P_b^{-1}}^2 + \lambda^2 \|D(x_k - x_k^b)\|^2 \right)$$

Where  $D$  and  $\lambda$  are the regularization functional and regularization parameter, respectively.

$$x_k^{aMAP} = \arg \min_{x_k} \frac{1}{2} \left( \lambda^2 \|D(x_k - x_k^b)\|^2 + \|x_k - x_k^a\|_{P_a^{-1}}^2 + C \right)$$

$$x_k^{aMAP} = x_k^a + P_k^a D^T [I + D P_k^a D]^{-1} (x_k^b - D x_k^a)$$

- The analysis step is carried out in two stages in PDA.

# Methodology – Data Assimilation

- **A Priori constraint: add the background model – 3D-VAR**
  - Objective function combining the deviation from the data and the model
  - **3D-VAR: estimate 3D structure of the unknown state**

$$x_k^a = \arg \min_{x_k} \frac{1}{2} \left( \|y_k - H_k x_k\|_{R_k^{-1}}^2 + \|x_k - x_k^b\|_{P_b^{-1}}^2 \right)$$

- Where  $R_k^{-1}$  and  $P_b^{-1}$  are the data error covariance and model error covariance, respectively.

- **We find that with the ingestion of upward looking data alone, the problem remains ill-posed.**
- **Hence, we further constrain the solution to be vertically smooth.**

$$x_k^{aMAP} = \arg \min_{x_k} \frac{1}{2} \left( \|y_k - H_k x_k\|_{R_k^{-1}}^2 + \|x_k - x_k^b\|_{P_b^{-1}}^2 + \lambda^2 \|D(x_k - x_k^b)\|^2 \right)$$

Where  $D$  and  $\lambda$  are the regularization functional and regularization parameter, respectively.

$$x_k^{aMAP} = \arg \min_{x_k} \frac{1}{2} \left( \lambda^2 \|D(x_k - x_k^b)\|^2 + \|x_k - x_k^a\|_{P_a^{-1}}^2 + C \right)$$

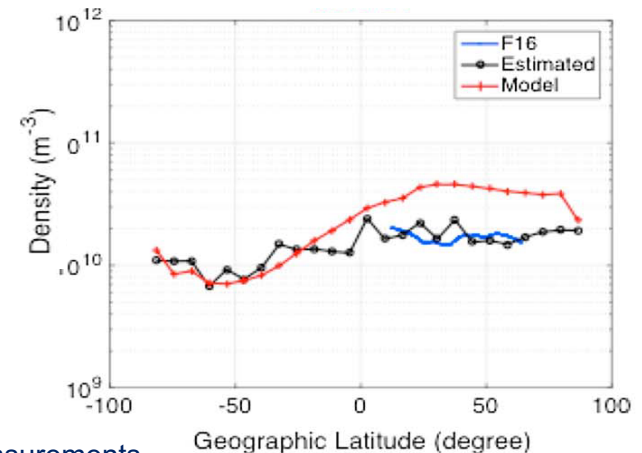
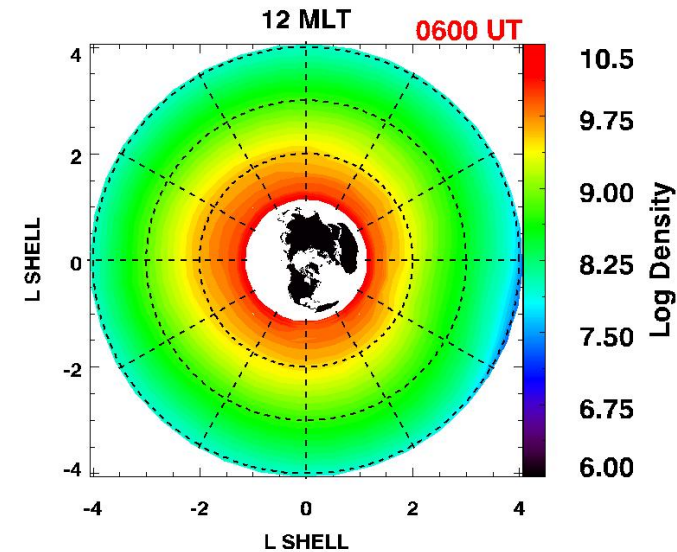
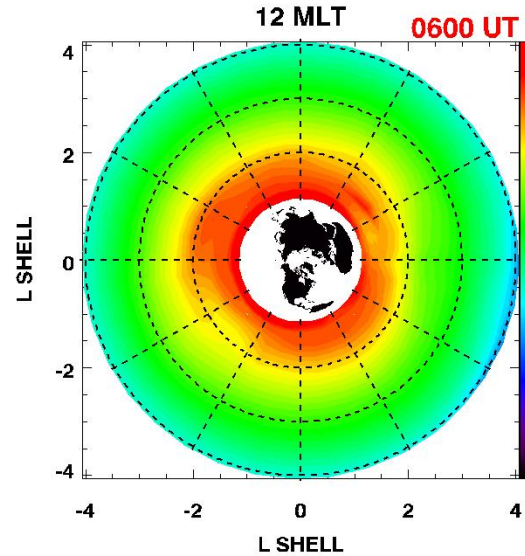
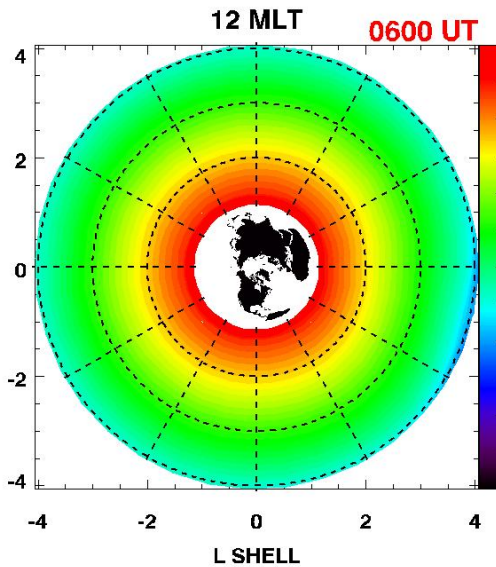
- **The analysis step is carried out in two stages in PDA.**
- **Move the state forward in time via Gauss-Markov Kalman.**

# An example of PDA Estimation results

Model

3DVAR

PDA



- Equatorial cross sections of the plasmasphere electron density ( $\text{m}^{-3}$ ).
- The cross sections extend to  $L=4$  (20,000 km).
- Sun is at the top of the image, dawn to the right.
- PDA eliminates unrealistic altitude gradients.
- A good agreement is demonstrated between DMSP-F16 in-situ densities and PDA estimated densities.

The authors are grateful to Dr. Hairston from UT Dallas for providing DMSP density measurements

Space APL

# Summary and Future Directions

- **Imposing a smoothness constraint is necessary to avoid non-physical gradients in the vertical direction**
- **An assimilative model that provides global 3D maps of electron density in the plasmasphere.**
- **A coupled ionosphere-plasmasphere data assimilation model\*\***
- **The extension of the PDA grid to lower ionospheric heights**
  - **Ground-based GPS TEC**
  - **ISR measurements**
  - **Ionosonde**
  - **FUV 135.6 nm radiance measurements**
- **The coupled ionosphere-plasmasphere model will allow more accurate specification, nowcast, and forecast of the upper atmosphere.**
  - **Evolution of the plasmasphere during a geomagnetic storm (plumes)**

\* NASA-HSR grant #NNX16AG65G, R. Bishop, A. Coster, G. Bust, R. Nikoukar, D. Turner, and C. Lemon, Storm-time Dynamics of the Plasmopause and the Ionosphere/Magnetosphere System, 2014-2016.

\*\* G. Bust, A. Chartier, R. Schaefer, R. Nikoukar, E. Miller, JHU/APL.



JOHNS HOPKINS  
APPLIED PHYSICS LABORATORY