

Joint Data Assimilation and Parameter Calibration in online groundwater modelling using Sequential Monte Carlo techniques

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A Introduction

Never heard of filtering?
Start here!

Motivation:

- Groundwater modelling is notoriously limited by availability of geological data

Classic approach:

- Inverse parameter calibration with batch of available data

Problem:

- Computational effort: with new data, lengthy recalibration is required

B Data assimilation

Why

- Models represent reality imperfectly
- For real-time applications, this drift can be corrected
- Assimilating observed data anchors the model in reality

How

- The system is described stochastically
- Introduction of model error: predictions are scattered
- Points close to observations form basis for next prediction
- Common techniques: Kalman filter or particle filter

Particle Filtering in a nutshell

In **deterministic systems**, each variable has a single scalar value. In **probabilistic systems**, variables take on all possible values at the same time. A probability density function (*pdf*) relates probabilities to the full range of possible outcomes.

Deterministic: Absolute knowledge (with image of a hand holding a coin)

Probabilistic: Anything's possible (with image of a hand holding dice)

C Online parameter calibration schemes

Extension of state vector:

- Cell parameters follow data assimilation trend, **requires linear relation^a**

Alternatives

- Small, random parameter changes, suffers heavily from **curse of dimensionality^b**

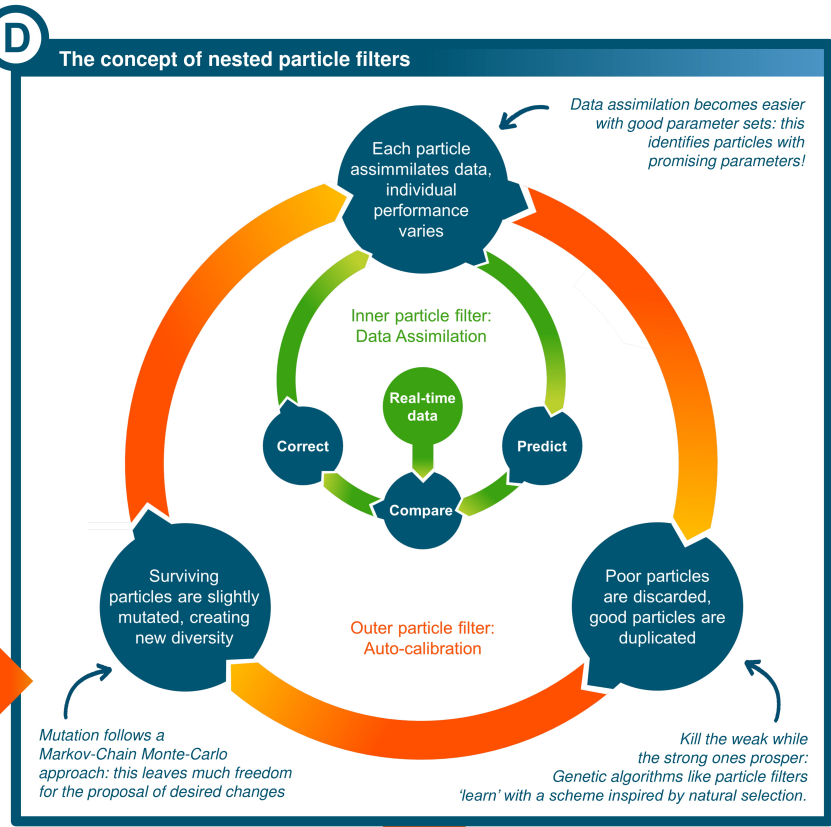
Chosen approach

Metropolis-Hastings MCMC:

- User may propose desired change^c
- Flexibility at a price:** implementation requires retracing the full model history during calibration step → **not online**

Solution hypothesis:

- The system is **ergodic**: it may suffice to only repeat the last *n* time steps
- Bounded computational effort → **online**



In probabilistic systems, a change in knowledge about a variable requires updating functions. This is done via the **Rule of Bayes:**

$$P(A|B) = \frac{P(A)P(B|A)}{P(B)}$$

Unfortunately, it is impossible to find an analytic solution to this Bayesian inference in all but the most simple cases (→ Kalman Filter).

Instead, analytic expressions are often **approximated** by a set of deterministic realizations, the eponymous **particles**:

Given enough of these particles, one could **draw from the set of outcomes** rather than the analytic function itself.

The technique of keeping this set representative of the underlying analytic function through reweighting and re-sampling is known as **particle filtering**.

E Preliminary results

Synthetic model setup:

- 2D model grid
- Hexagonal cells
- North: Neumann BC (max. 1E-7 m·s⁻¹)
- South: fixed head BC
- High-transmissivity zone through valley
- 7 observation wells (●)

Ensemble:

- 40 parameter particles
- 30 state particles
- Prior belief: *transmissivity is assumed uniform*
- BCs: *known precisely*

Results:

- Algorithm quickly identifies parameter sets yielding **equivalent solutions**
- Best performance** near regions of high head amplitudes (e.g. north-eastern edge)

Outlook:

- Draw state observations from more **complex synthetic model** (introducing true structural error)
- Investigate performance for **poorly defined boundary conditions**

Hydraulic head isolines:

- ensemble mean
- - - synthetic reference

Hexagonal grids maximize structural isotropy, tessellate perfectly and do not require ghost node correction.

Any questions remaining? Please ask!