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TIDE
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Transforming energy Infrastructure
through Digital Engineering

Inferring nonlinear internal wave currents from sparse observations

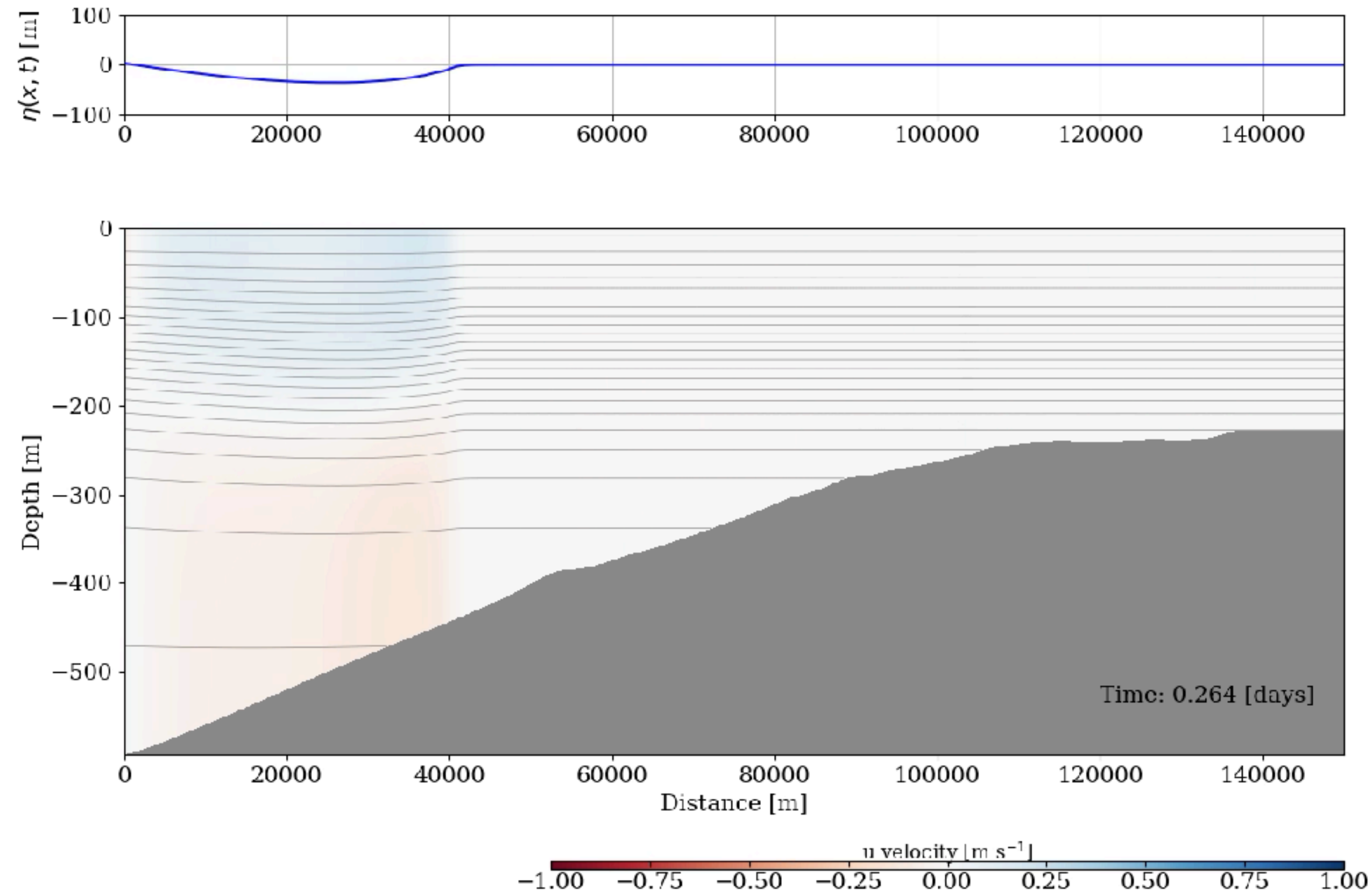
Lachlan Astfalck, Andrew Zurberti, Matt Rayson, Edward Cripps, and Nicole Jones

The University of Western Australia

Presented to the 2022 FOO/ACOMO Combined Workshop

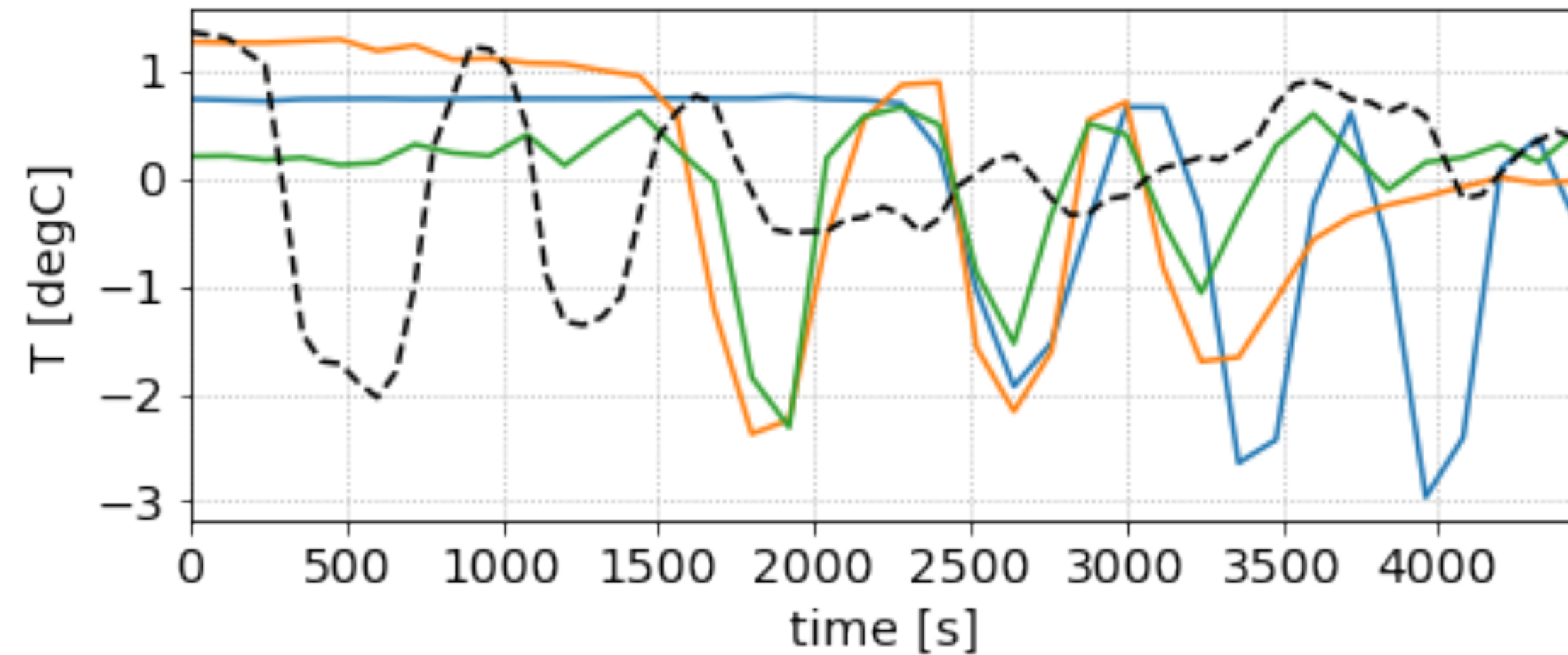
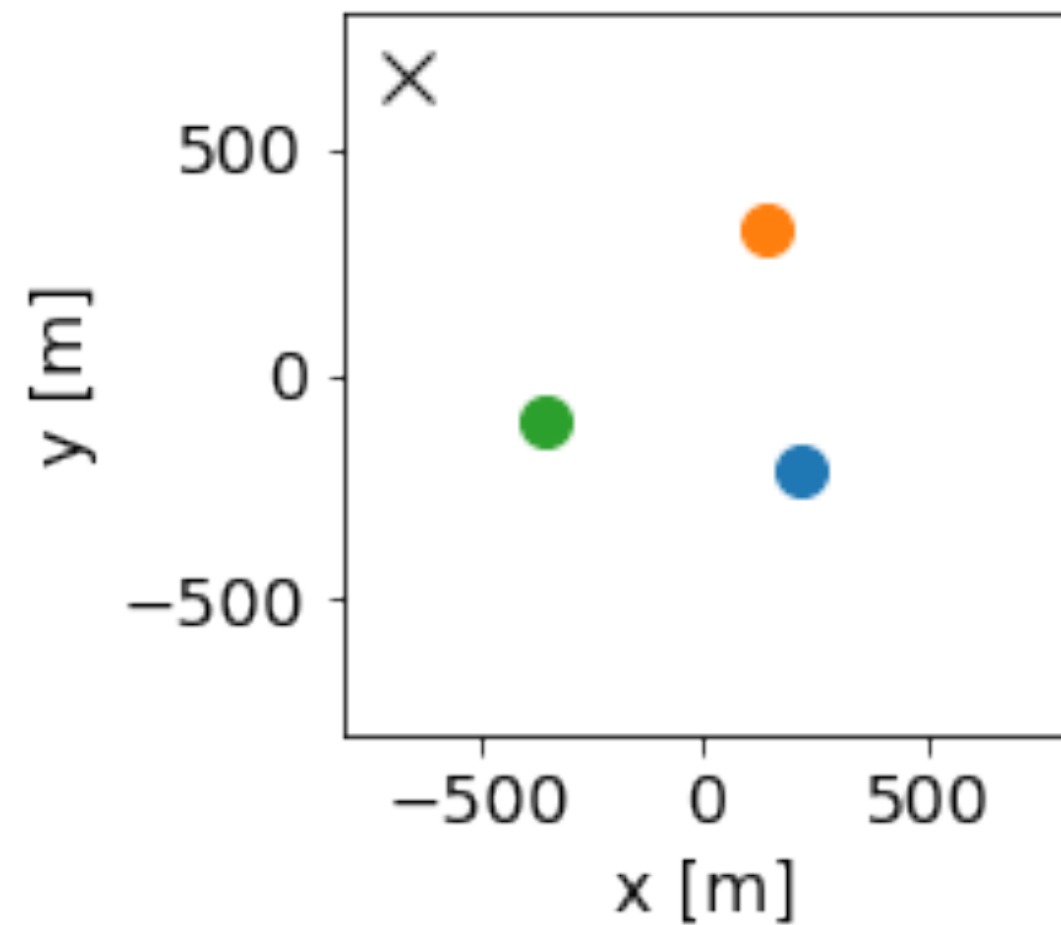
What are nonlinear internal waves...?

Nonlinear internal waves (NLIWs) are generated from the steepening of the internal tides into large aperiodic internal waves.



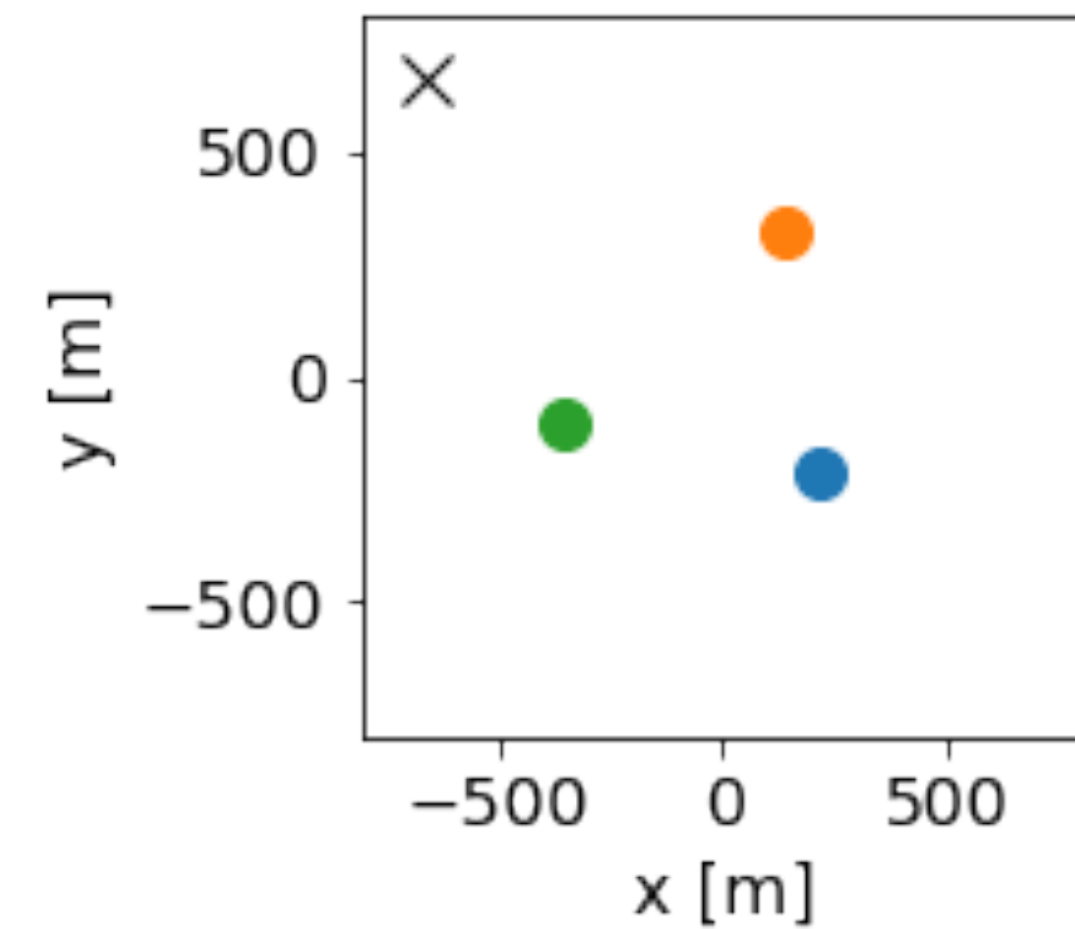
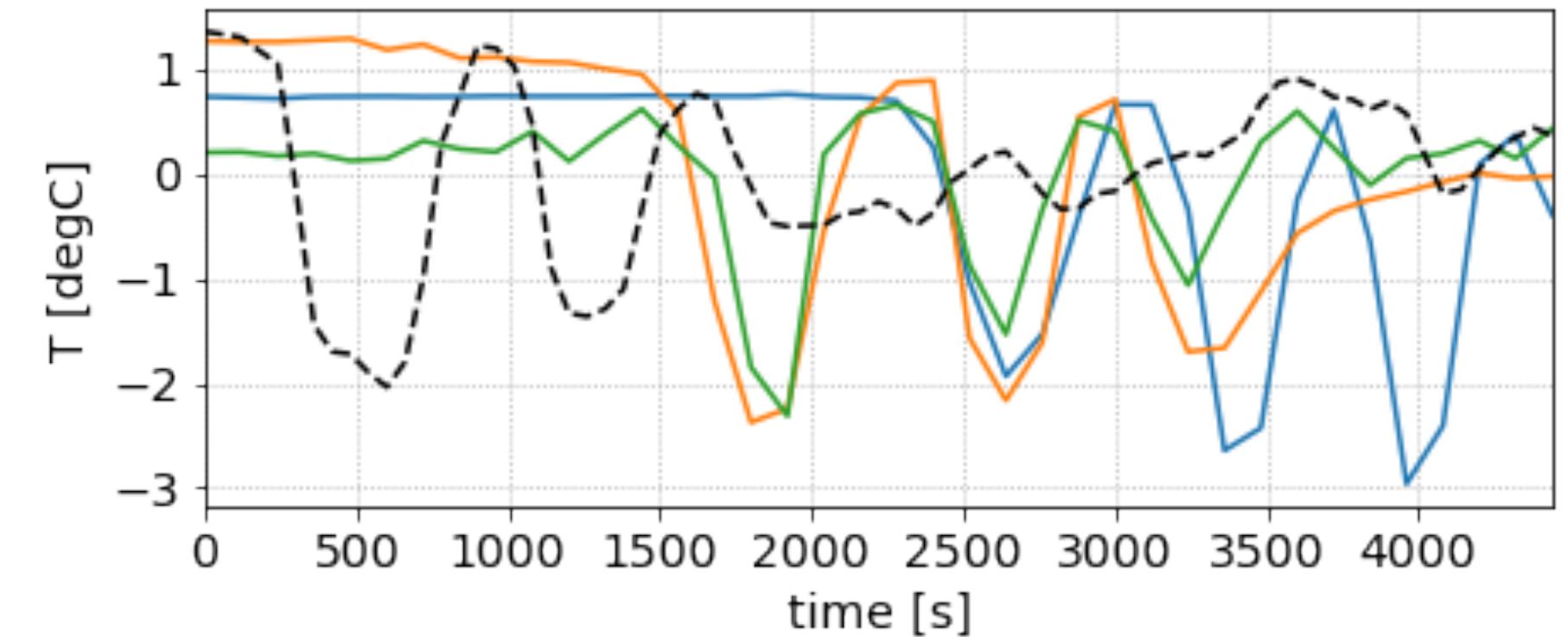
...and why do we care?

NLIWs generate extreme currents which dictate design criteria for many structures on the continental shelf.



How, historically, are internal waves modelled?

- Numerical modelling (3D non-hydrostatic Reynolds-averaged ocean models)
 - Too computationally expensive
- Regression (cnoidal wave functions)
 - Functions too restrictive
- Machine learning (neural networks)
 - No physical interpretability



Synthesising physics and statistical learning

- A Gaussian process is an infinite dimensional prior distribution over functions



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- Spatio-temporal structure is captured by the mean and covariance functions



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- We parameterise NLIW (and potentially other) structure into these functions



Synthesising physics and statistical learning

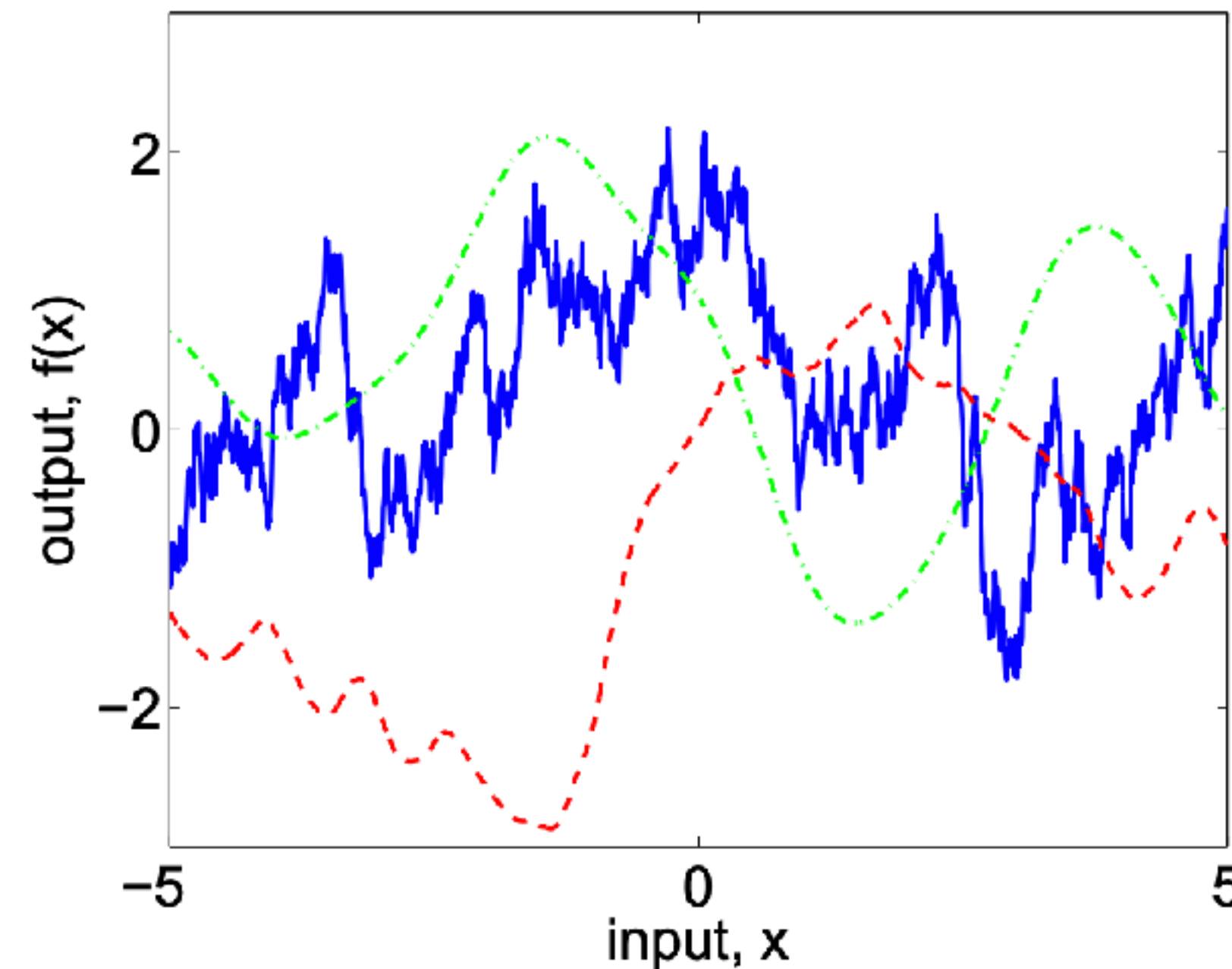
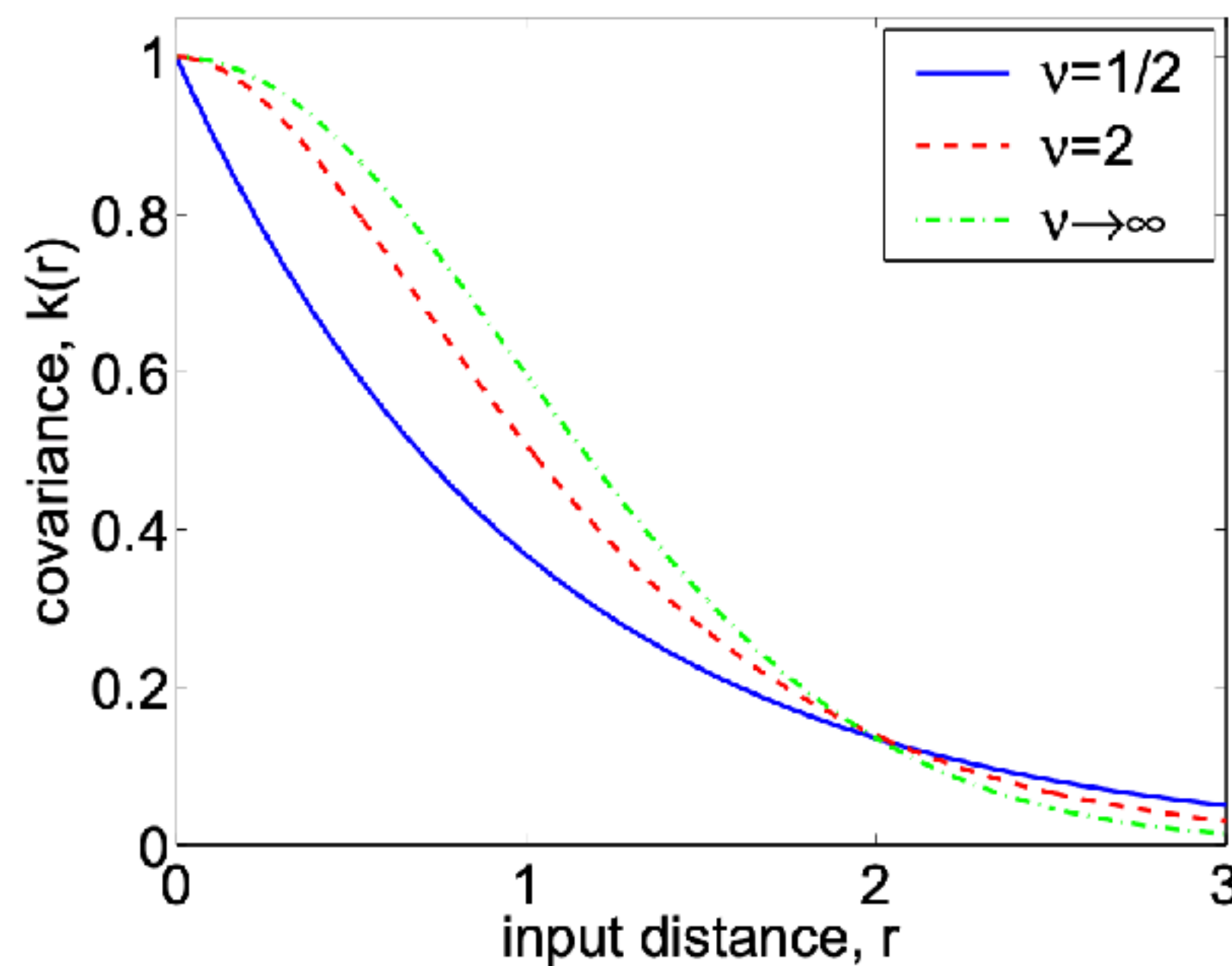
- ~~A Gaussian process is an infinite dimensional prior distribution over functions~~
- A Gaussian process is a big multivariate normal distribution
- Spatio-temporal structure is captured by the mean and covariance functions
- We parameterise NLIW (and potentially other) structure into these functions
- Similar to Kriging and Optimal Interpolation, BUT, offers a robust way to infer parameters



Embedding structure into the covariance

A covariance function, $k(\cdot, \cdot)$, describes the covariance between two locations.

A Matérn covariance function with different parameterisations:



Embedding structure into the covariance



Embedding structure into the covariance

For multivariate (space and time) inputs $\mathbf{x} = (x, y, t)$ and $\mathbf{x}' = (x', y', t')$



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Stationarity (covariance a function of distance in input space):

$$k(\mathbf{x}, \mathbf{x}') = k(|\mathbf{x} - \mathbf{x}'|, 0) = k(\tau), \text{ where } \tau = |\mathbf{x} - \mathbf{x}'|$$



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$$k(\mathbf{x}, \mathbf{x}') = \sigma^2 k_x(x, x') k_y(y, y') k_t(t, t')$$



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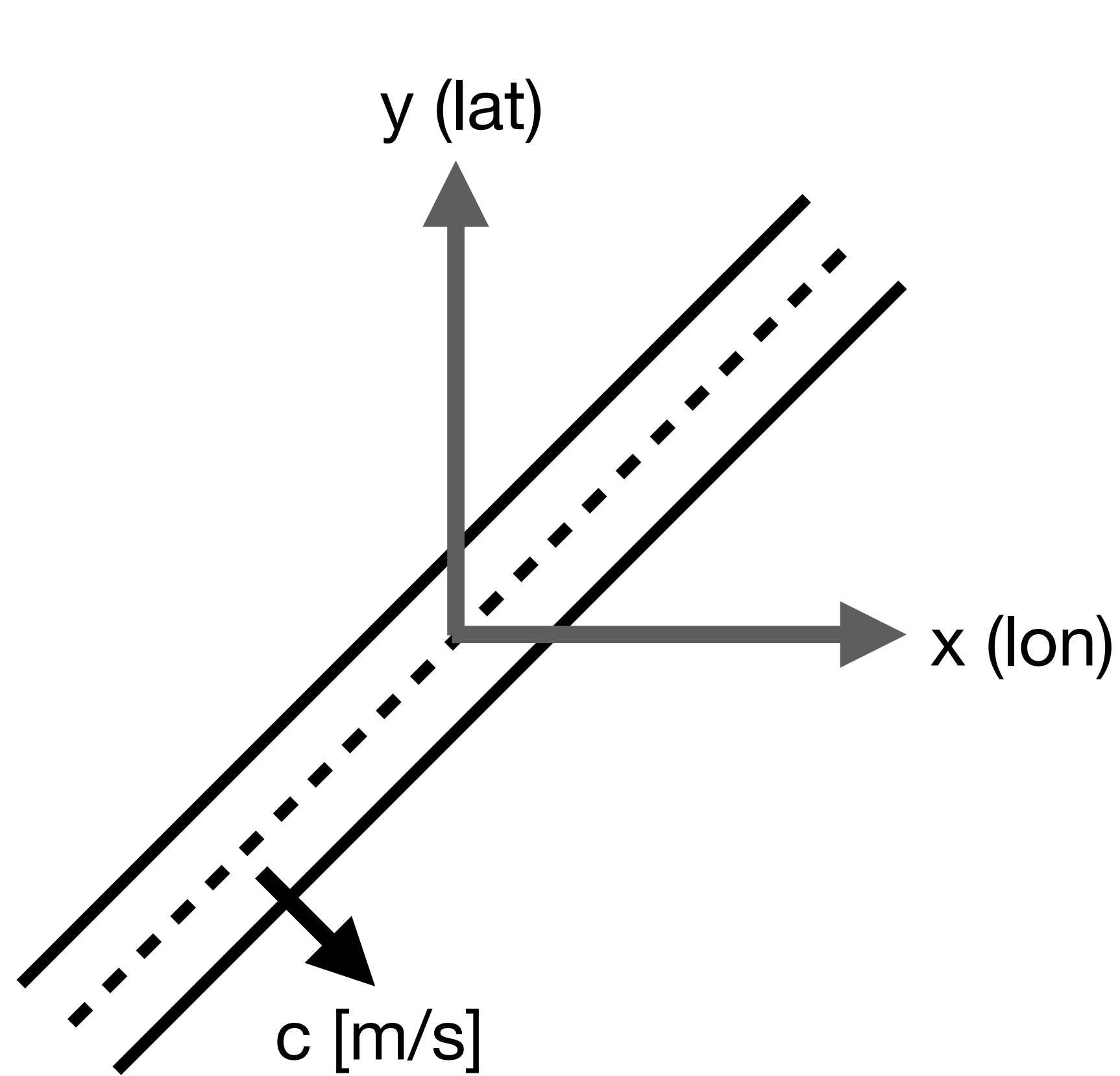
$$k(\mathbf{x}, \mathbf{x}') = \sigma^2 k_x(x, x') k_y(y, y') k_t(t, t')$$

Anisotropy (covariance in each dimension is different):

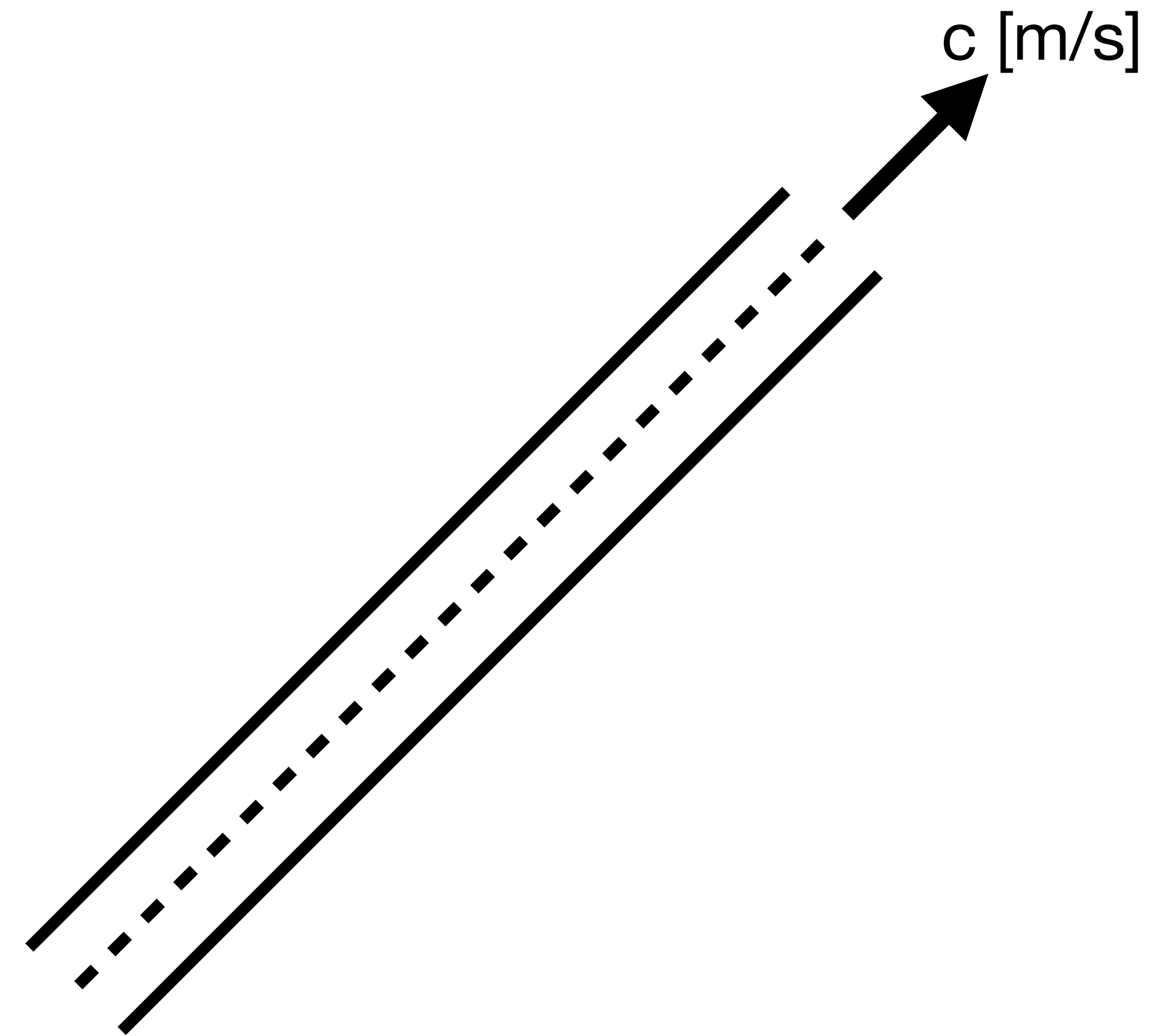
$$k_i(\cdot, \cdot) \neq k(\cdot, \cdot), \text{ for } i \in \{x, y, t\}$$



Embedding *NLIW dynamics* into the covariance



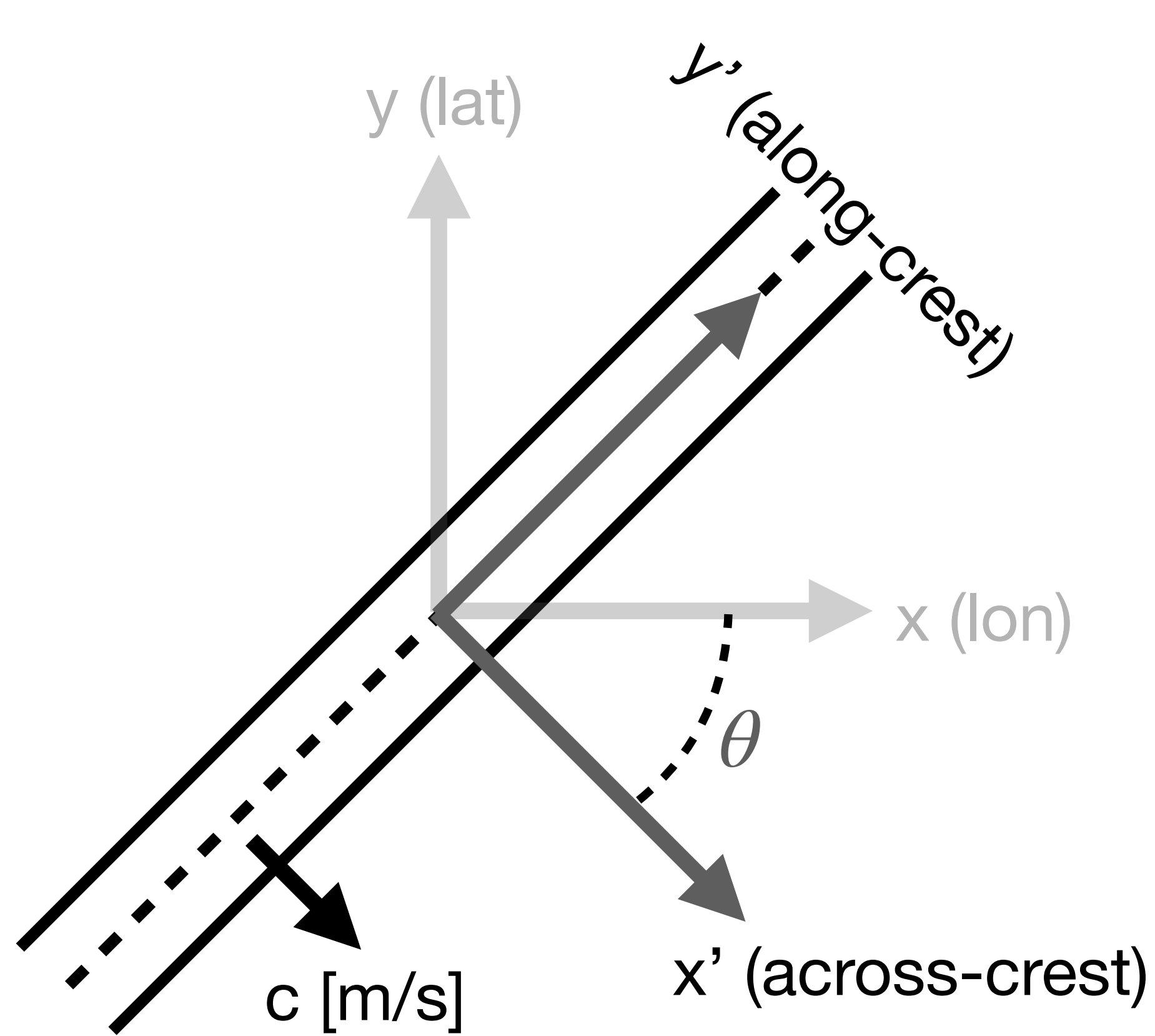
Latitude/Longitude Projection



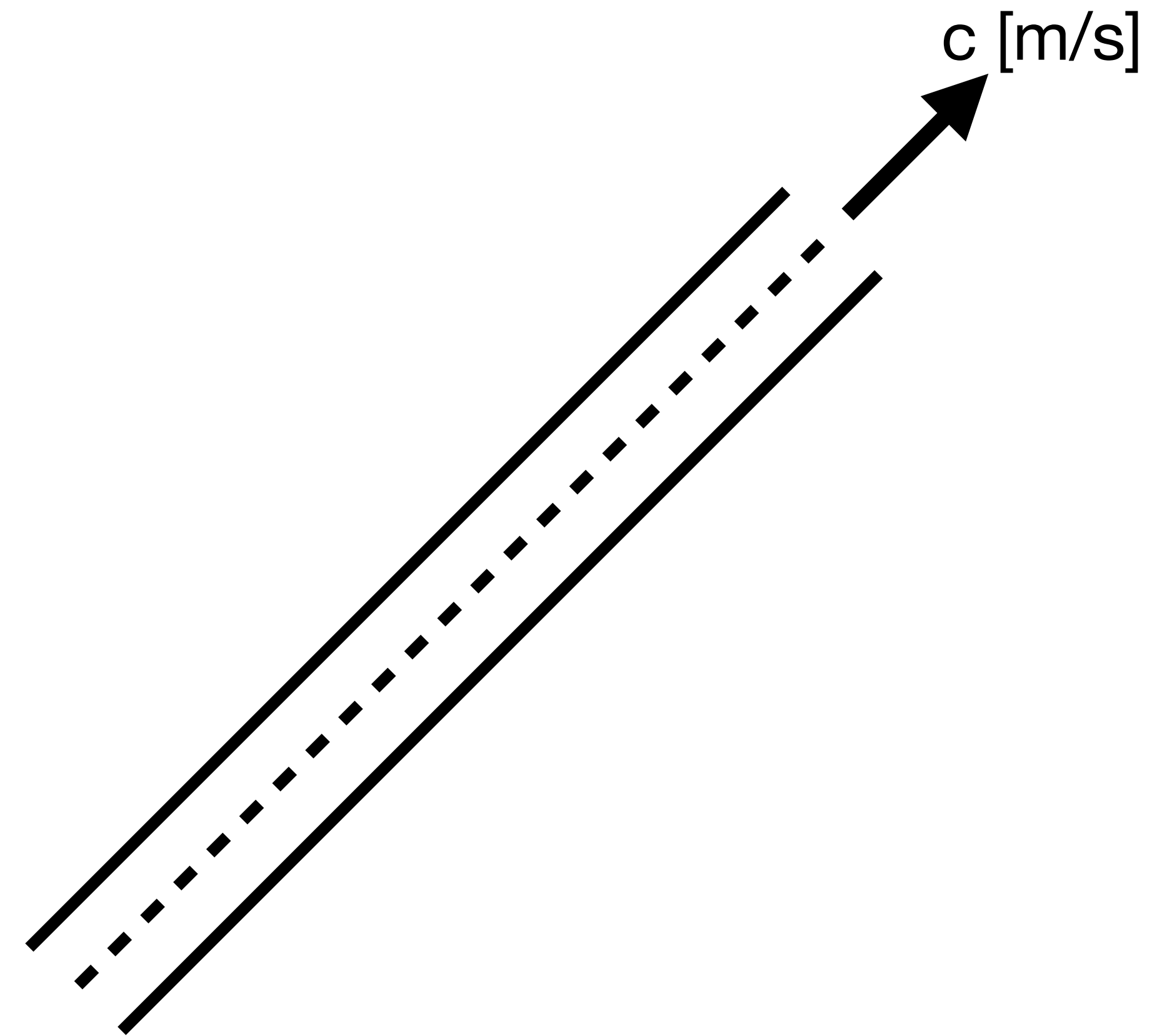
Across-crest/Time Projection



Embedding *NLIW* dynamics into the covariance



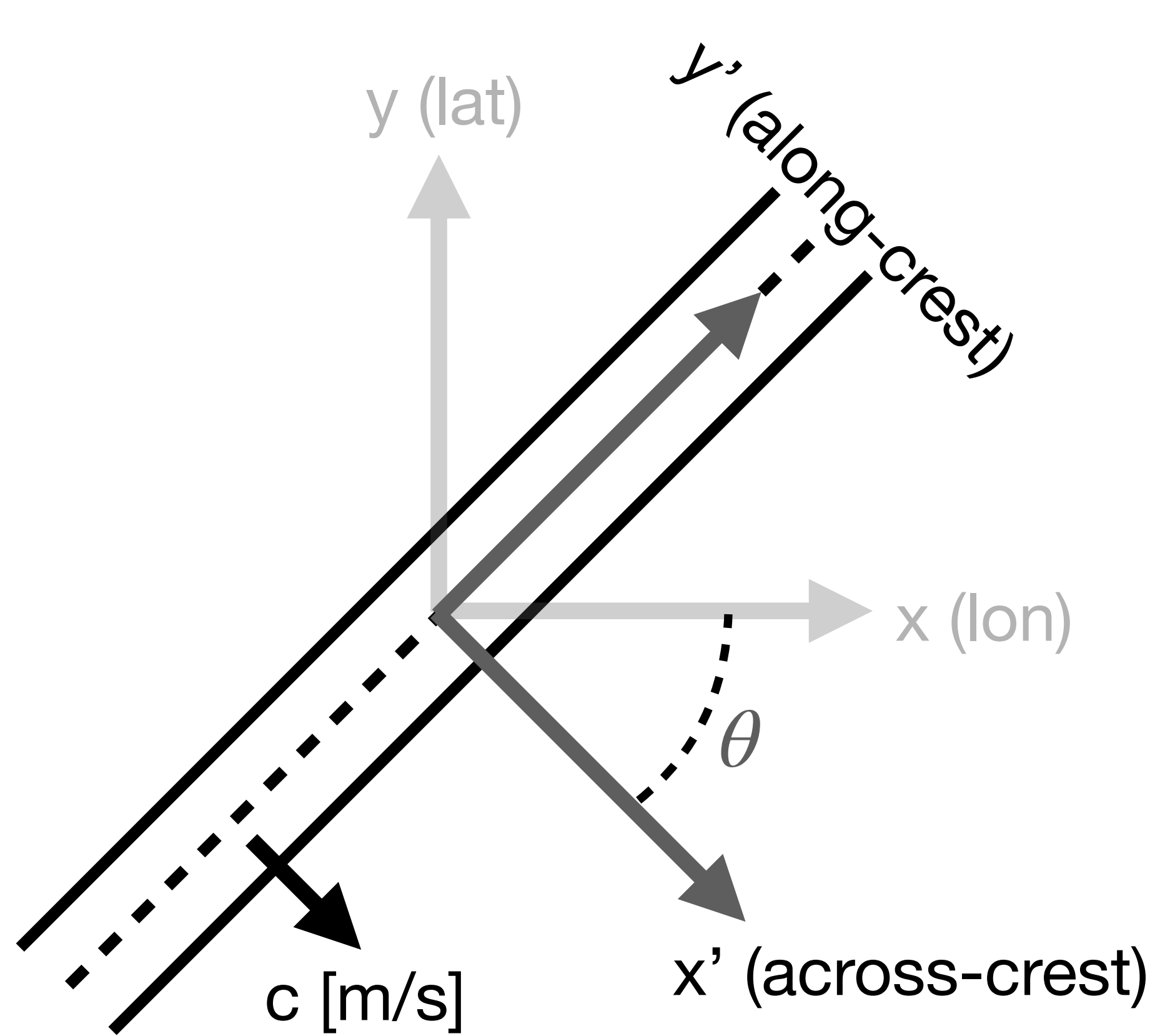
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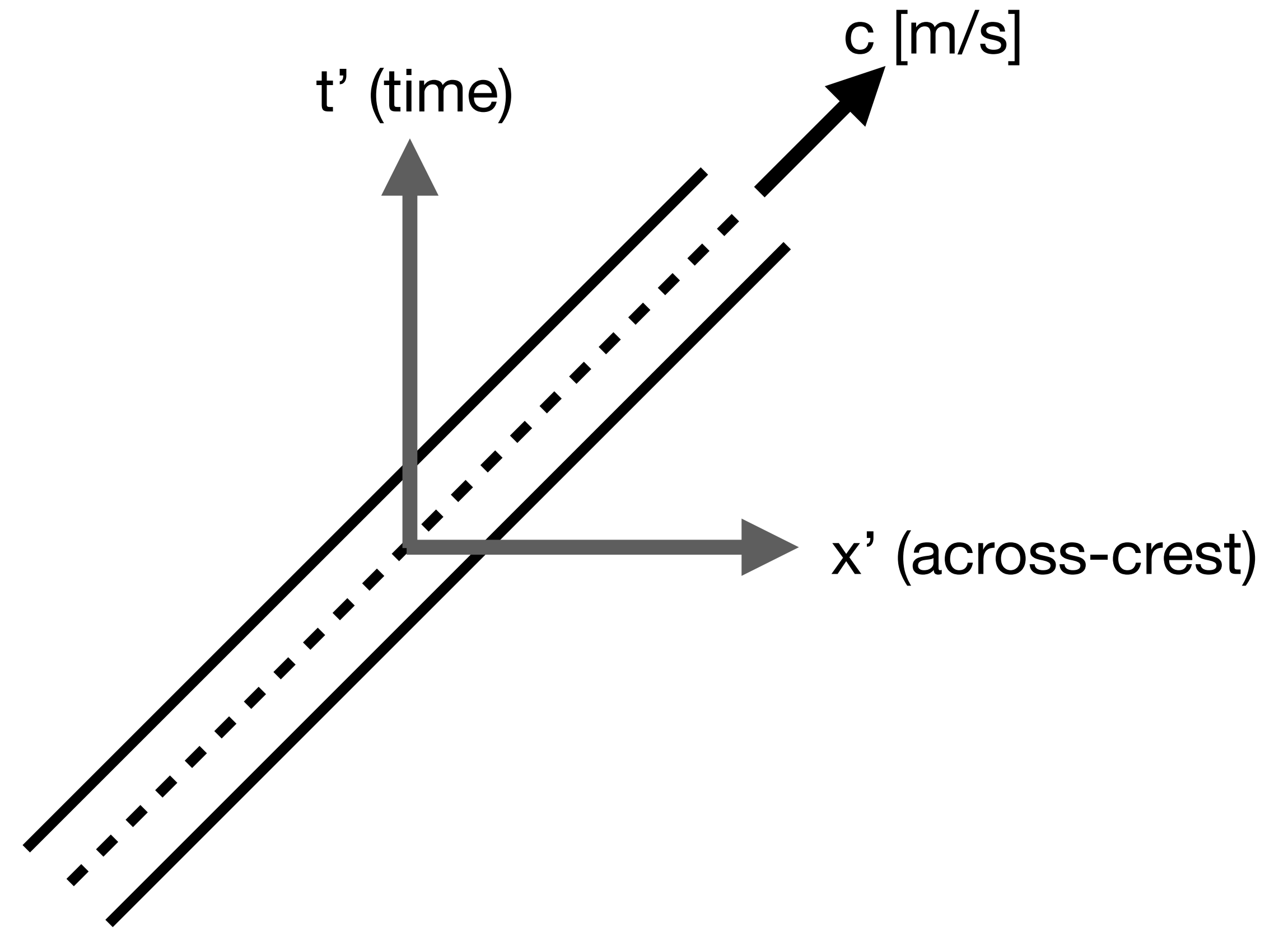
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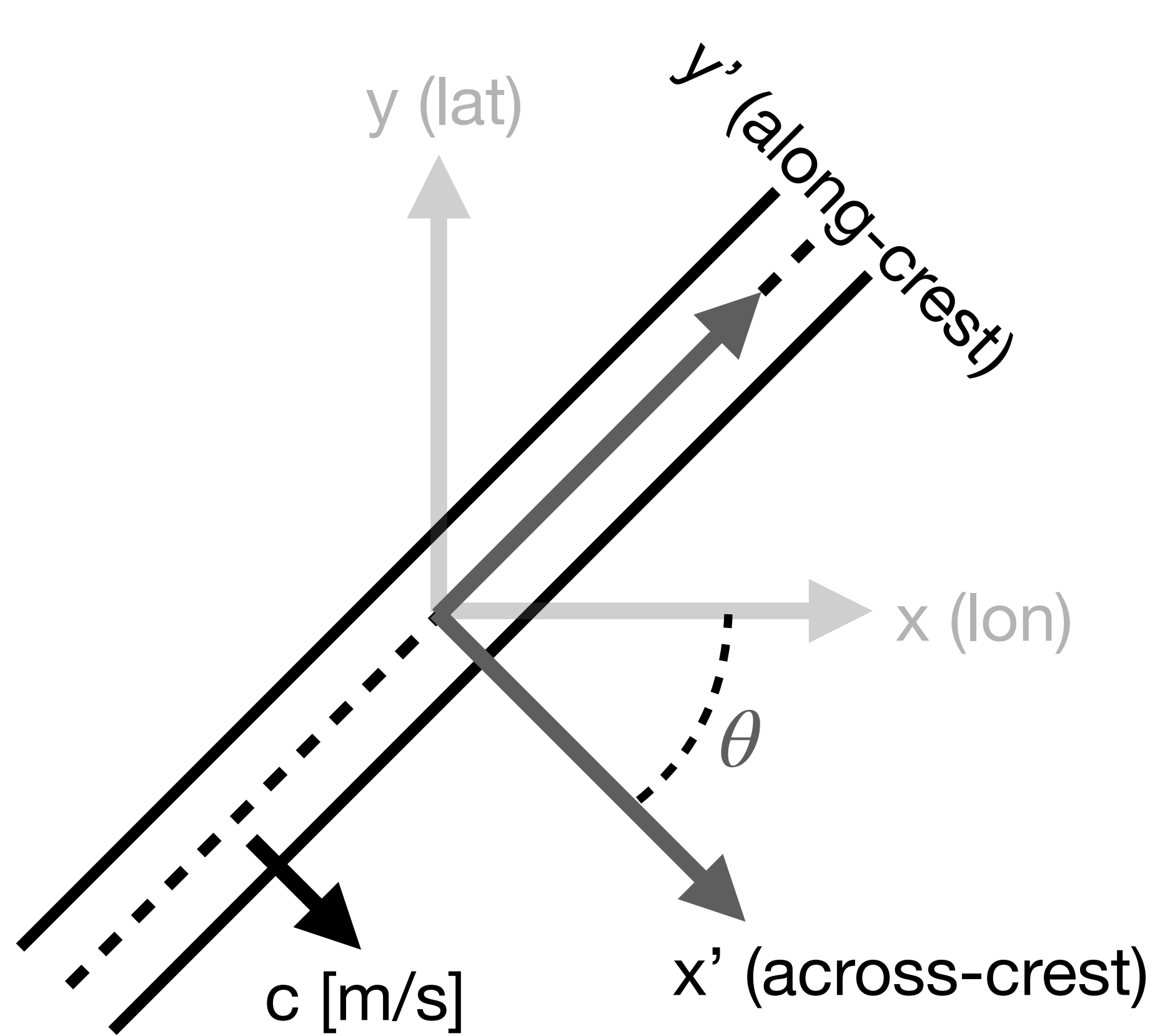
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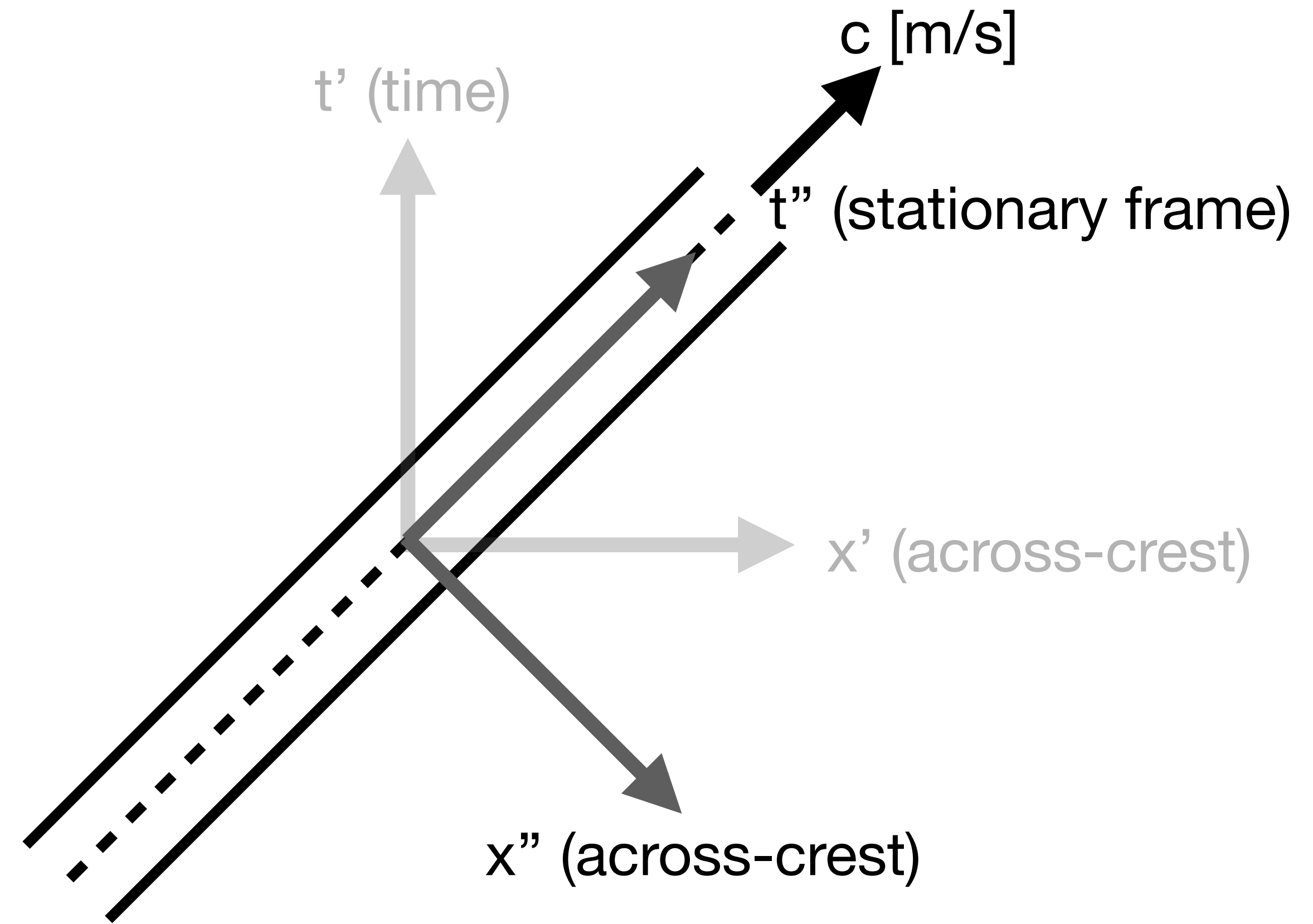
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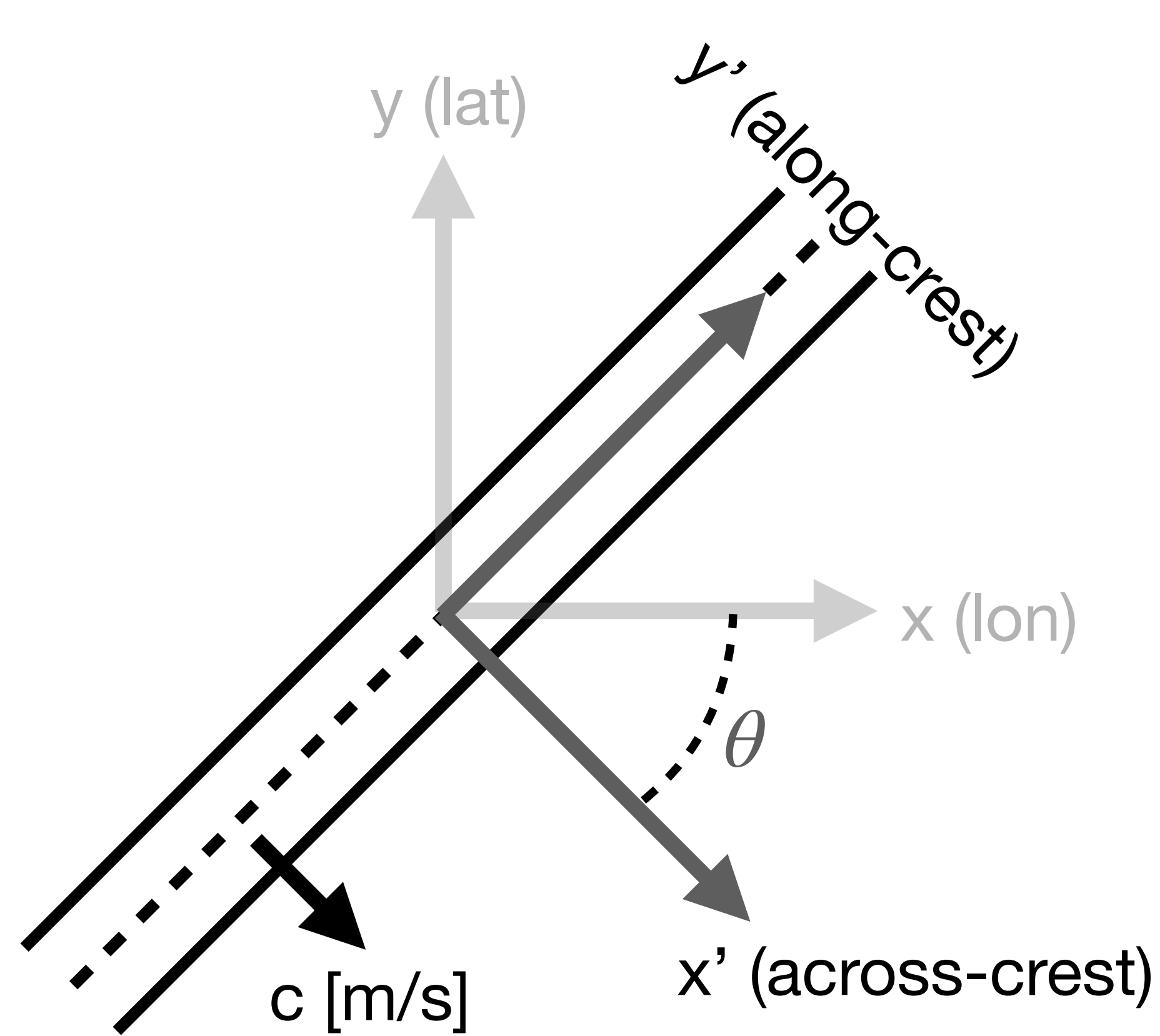
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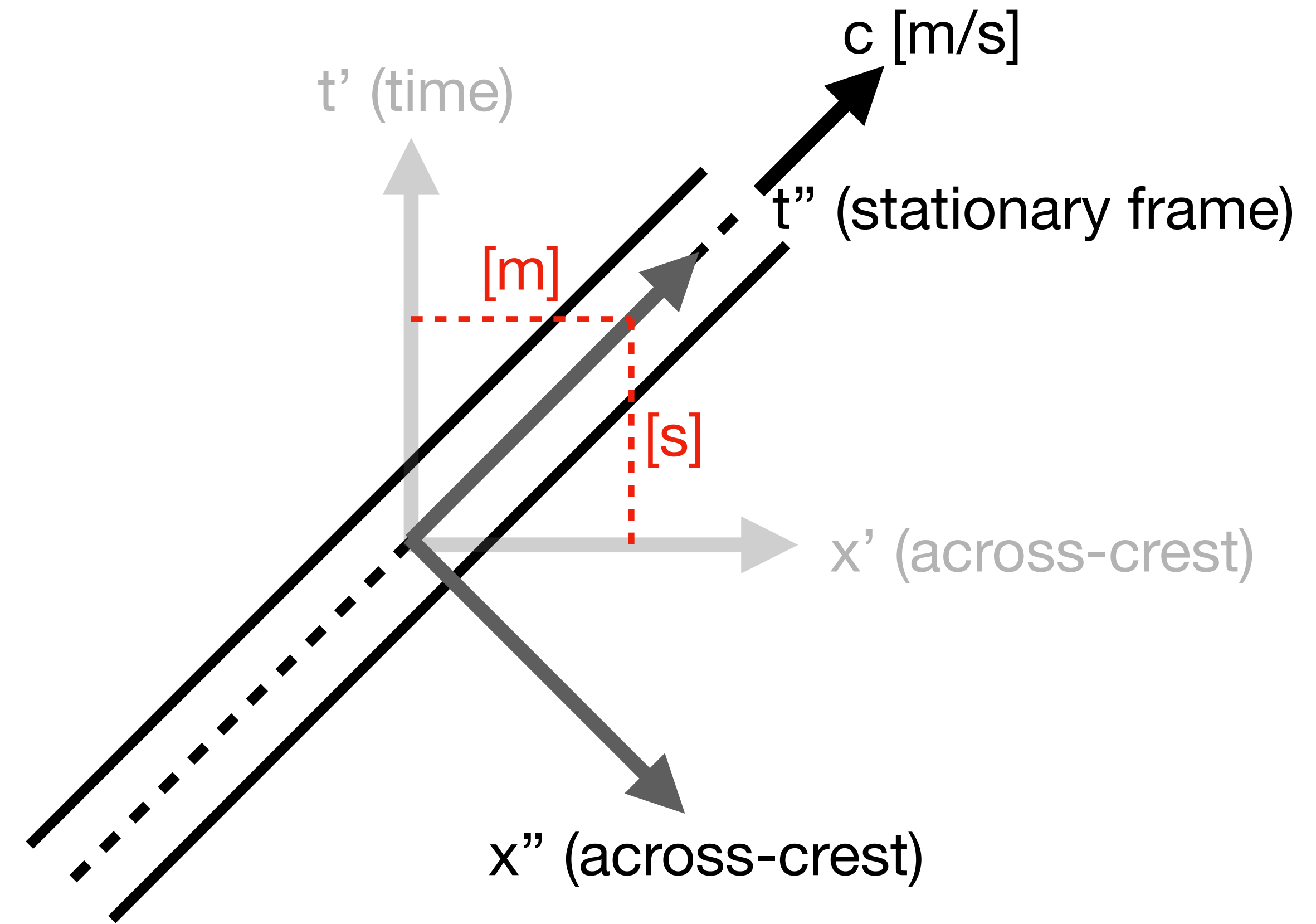
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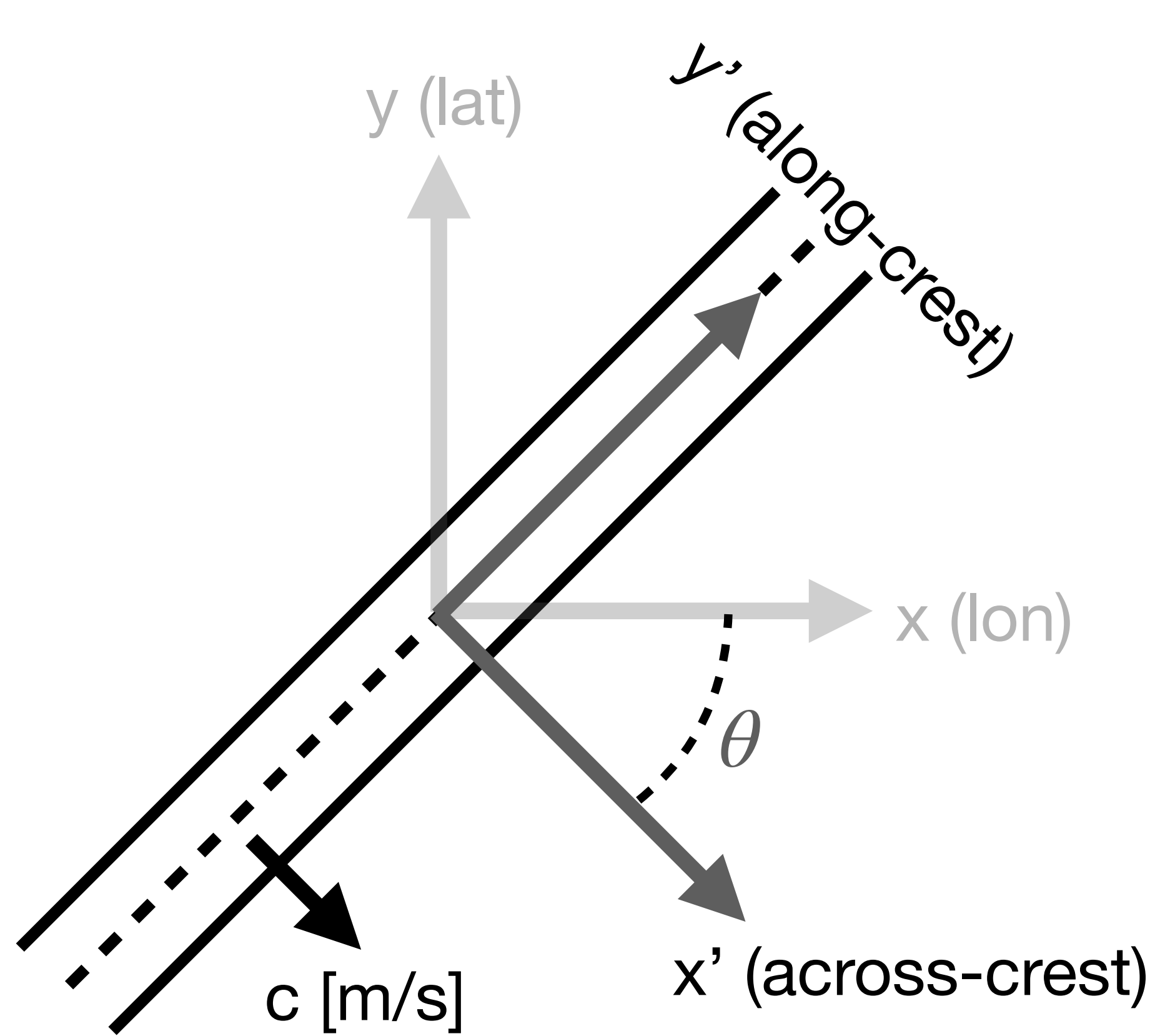
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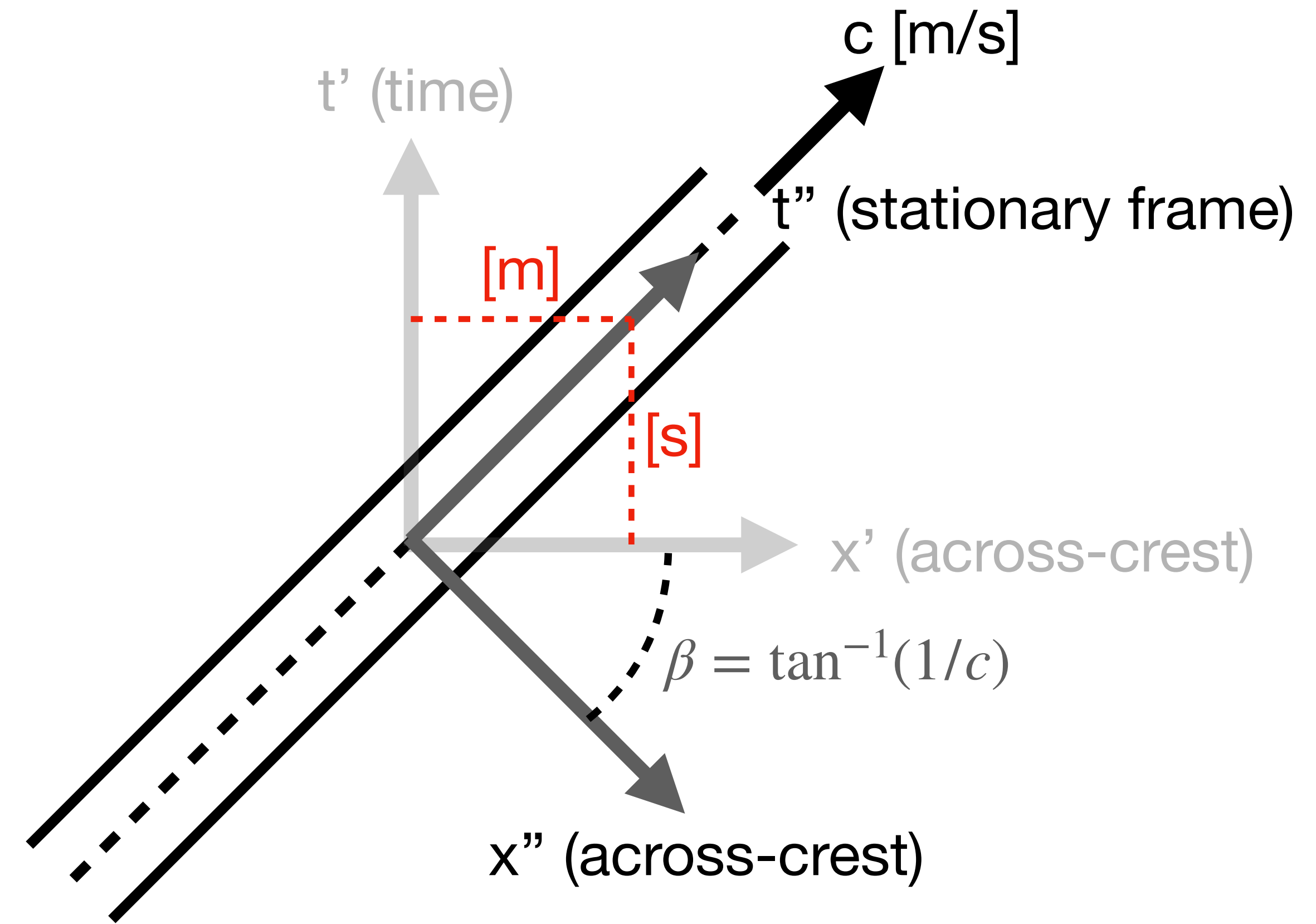
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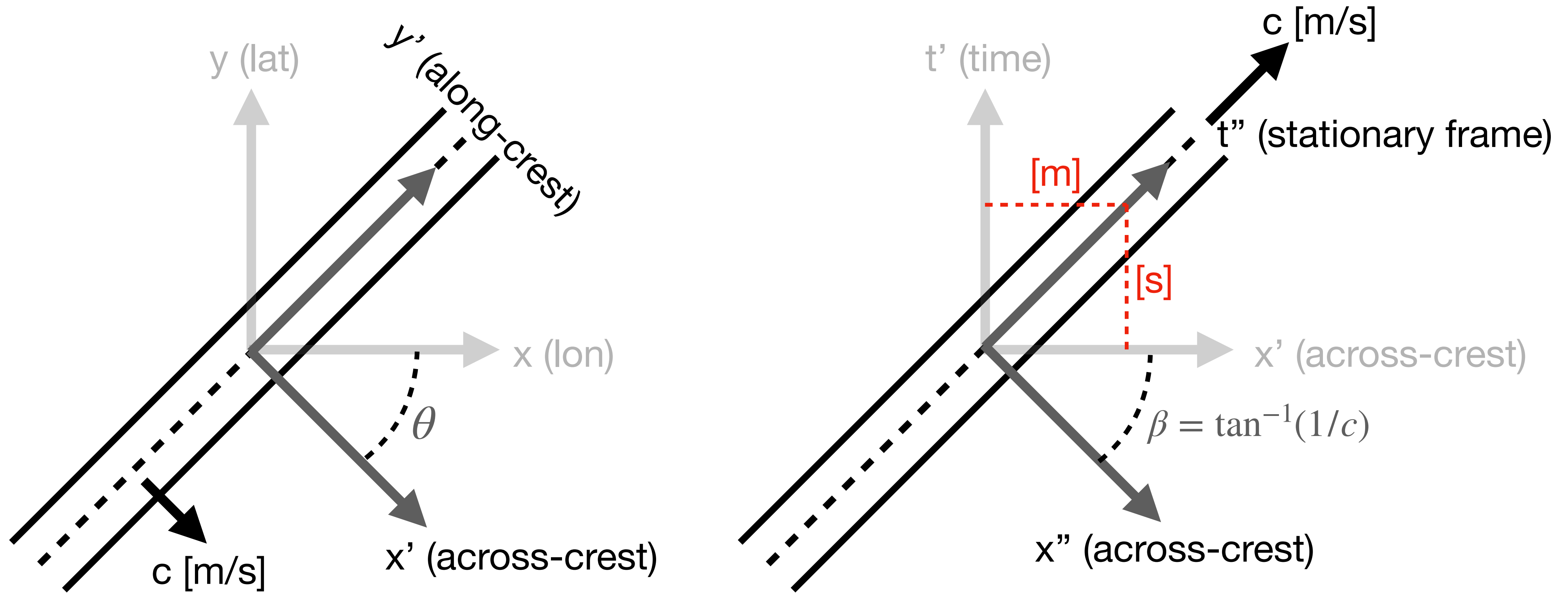
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Across-crest/Time Projection

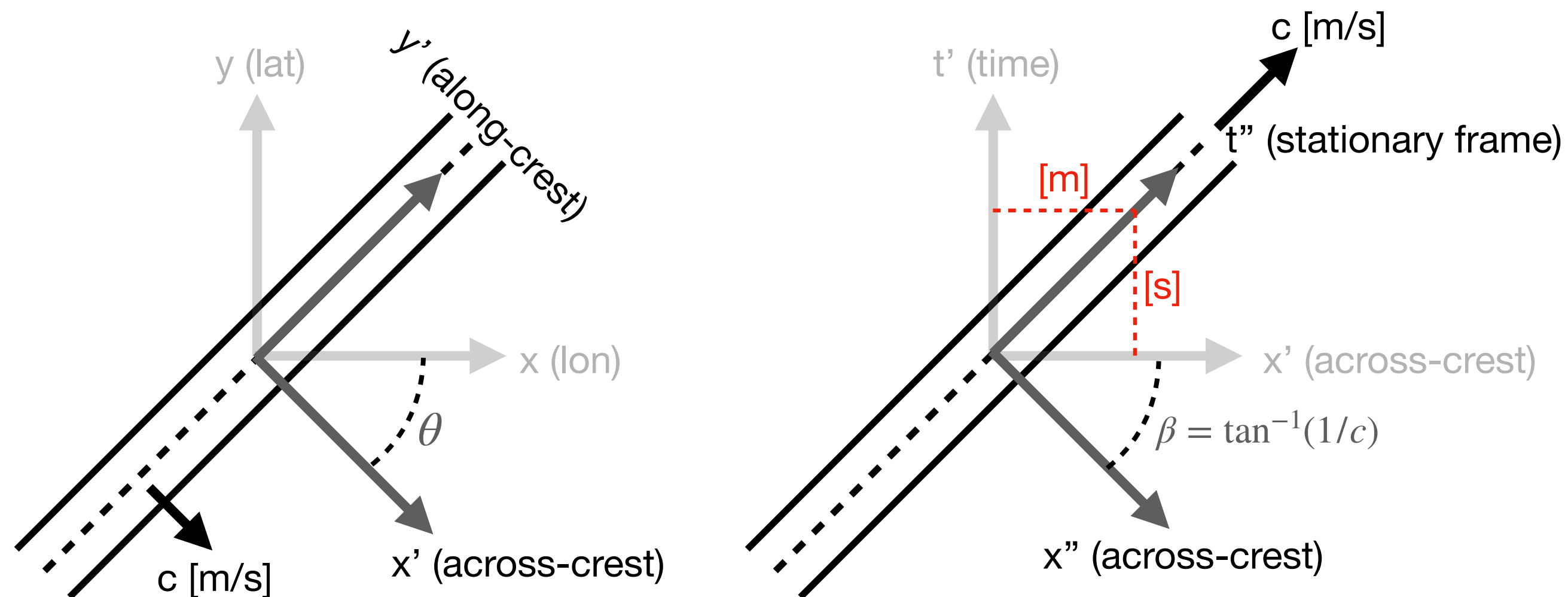


Embedding *NLIW* dynamics into the covariance



Embedding *NLIW dynamics* into the covariance

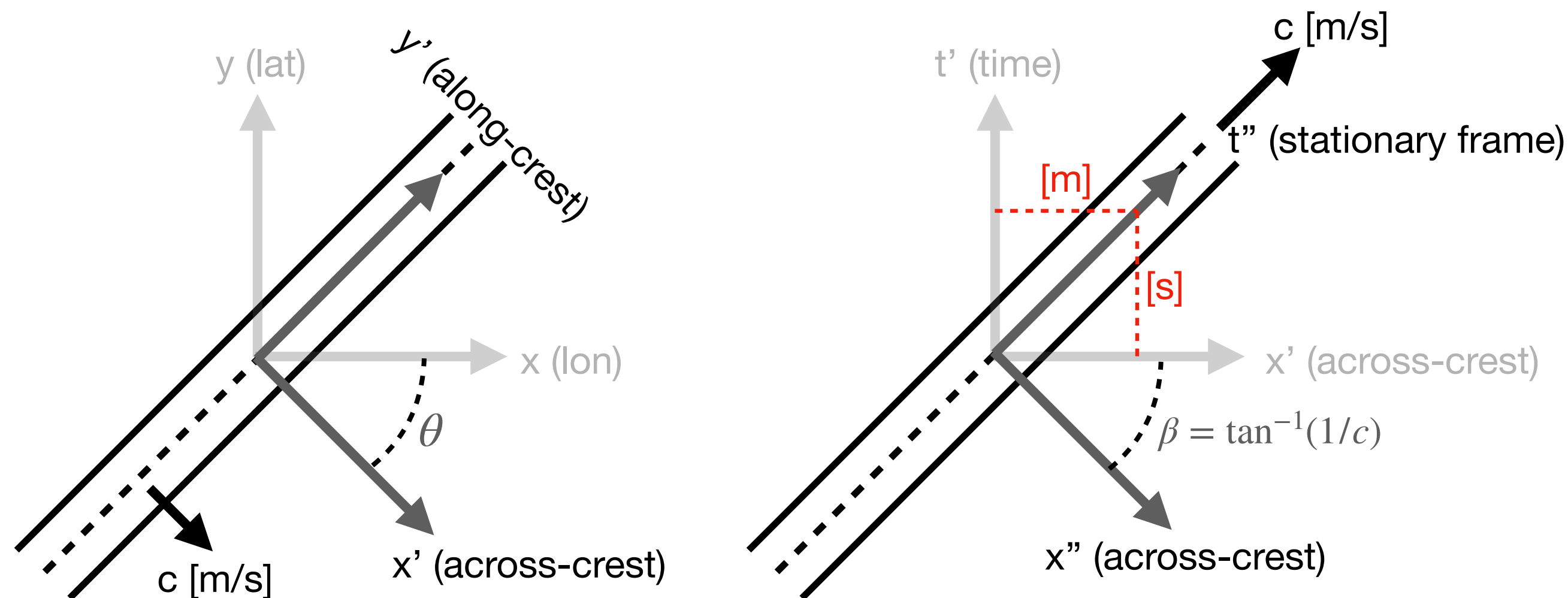
$$k_{\text{NLIW}}(\tau; \theta) = \sigma^2 k_{x''}(\tau_{x''}; \theta) k_{y''}(\tau_{y''}; \theta) k_{t''}(\tau_{t''}; \theta)$$



Embedding *NLIW dynamics* into the covariance

Across-crest

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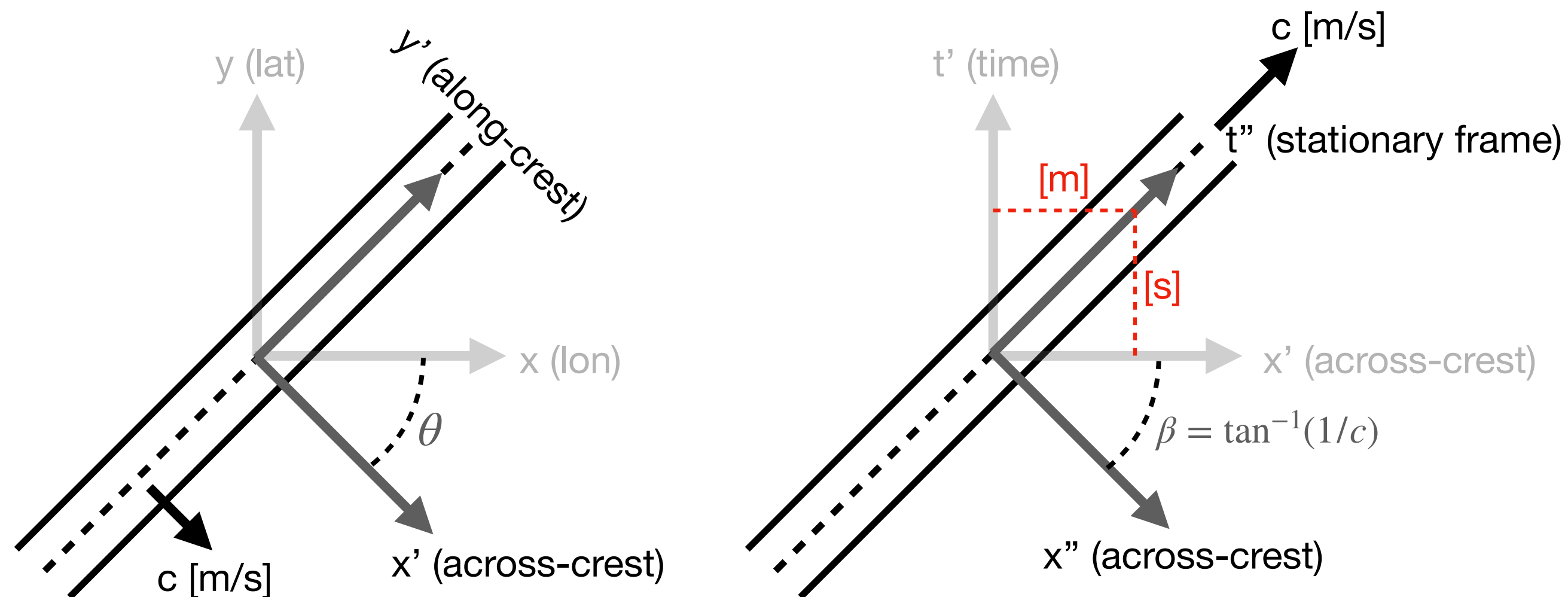


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Across-crest

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Along-crest

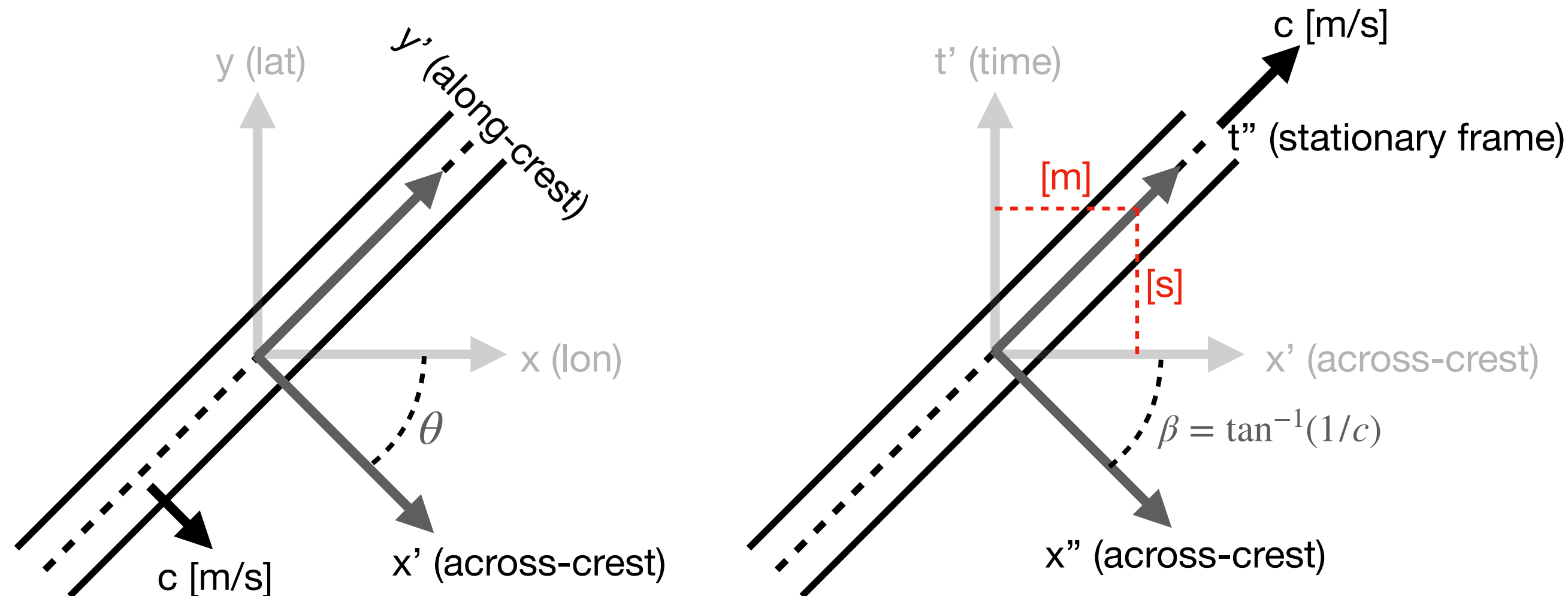


Embedding *NLIW dynamics* into the covariance

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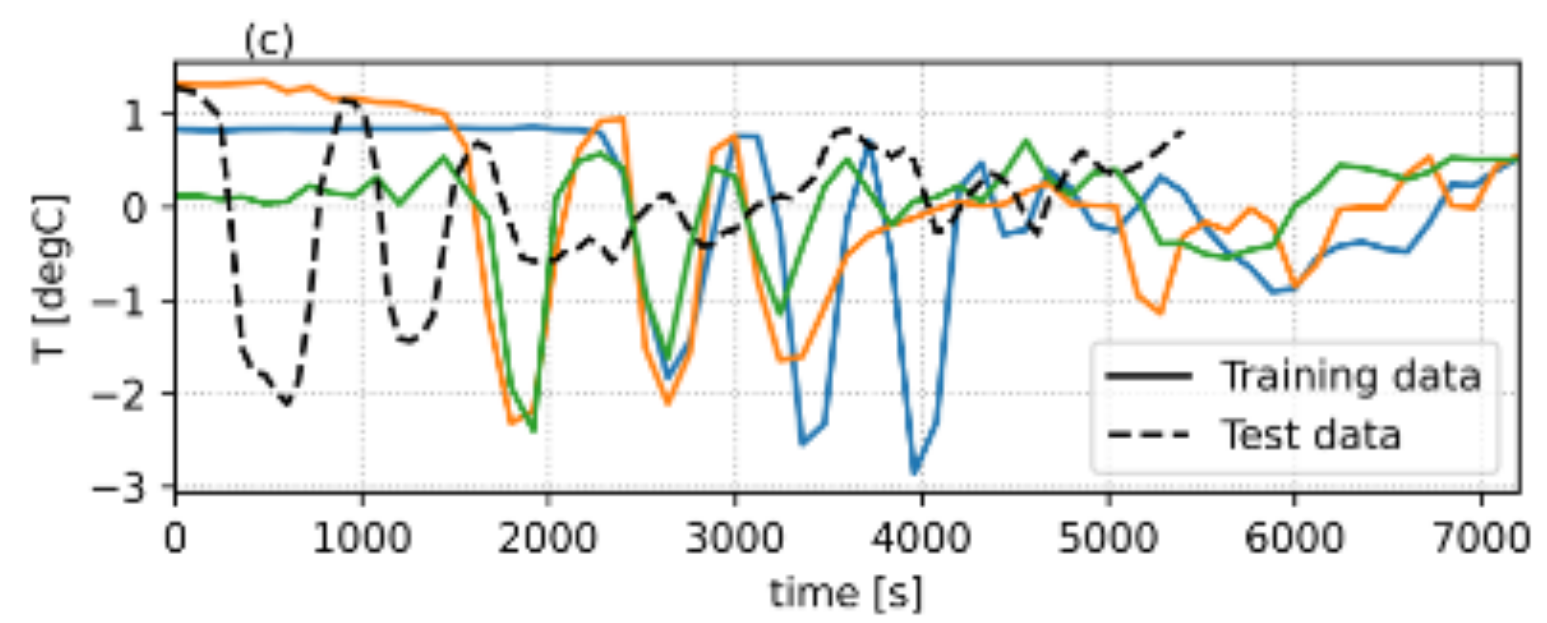
Across-crest Decay Term

Along-crest

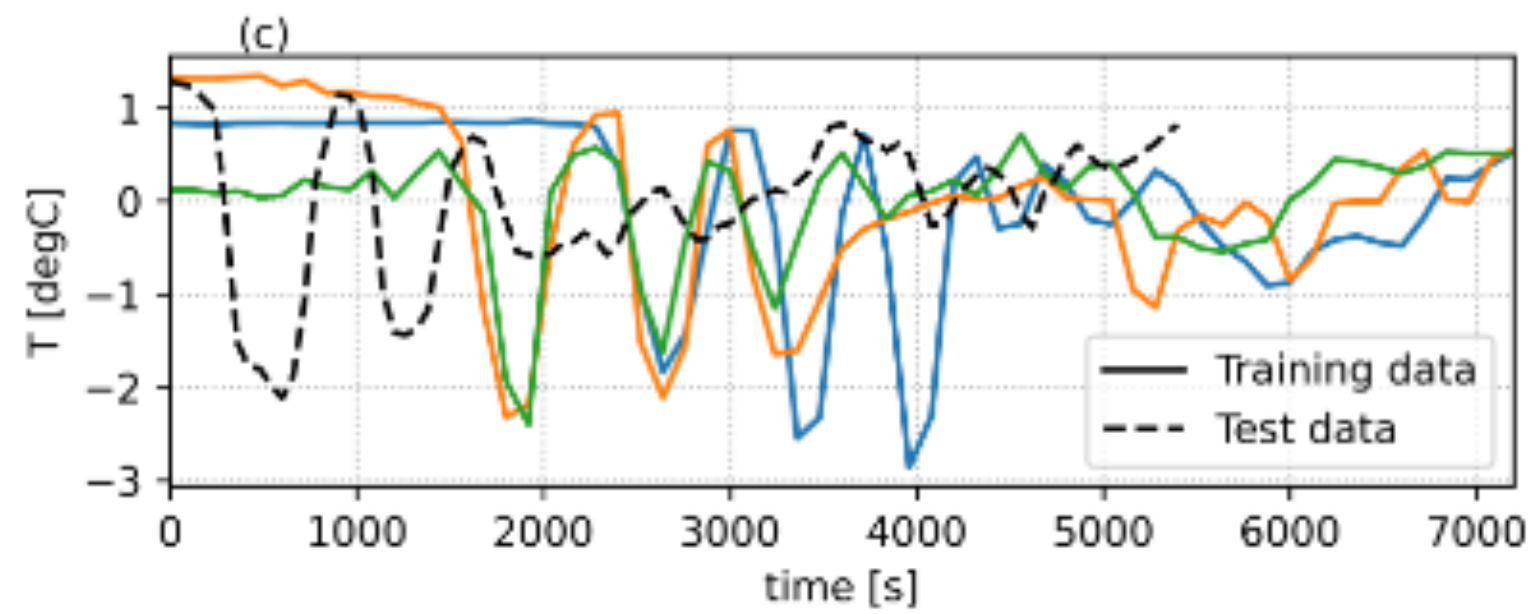
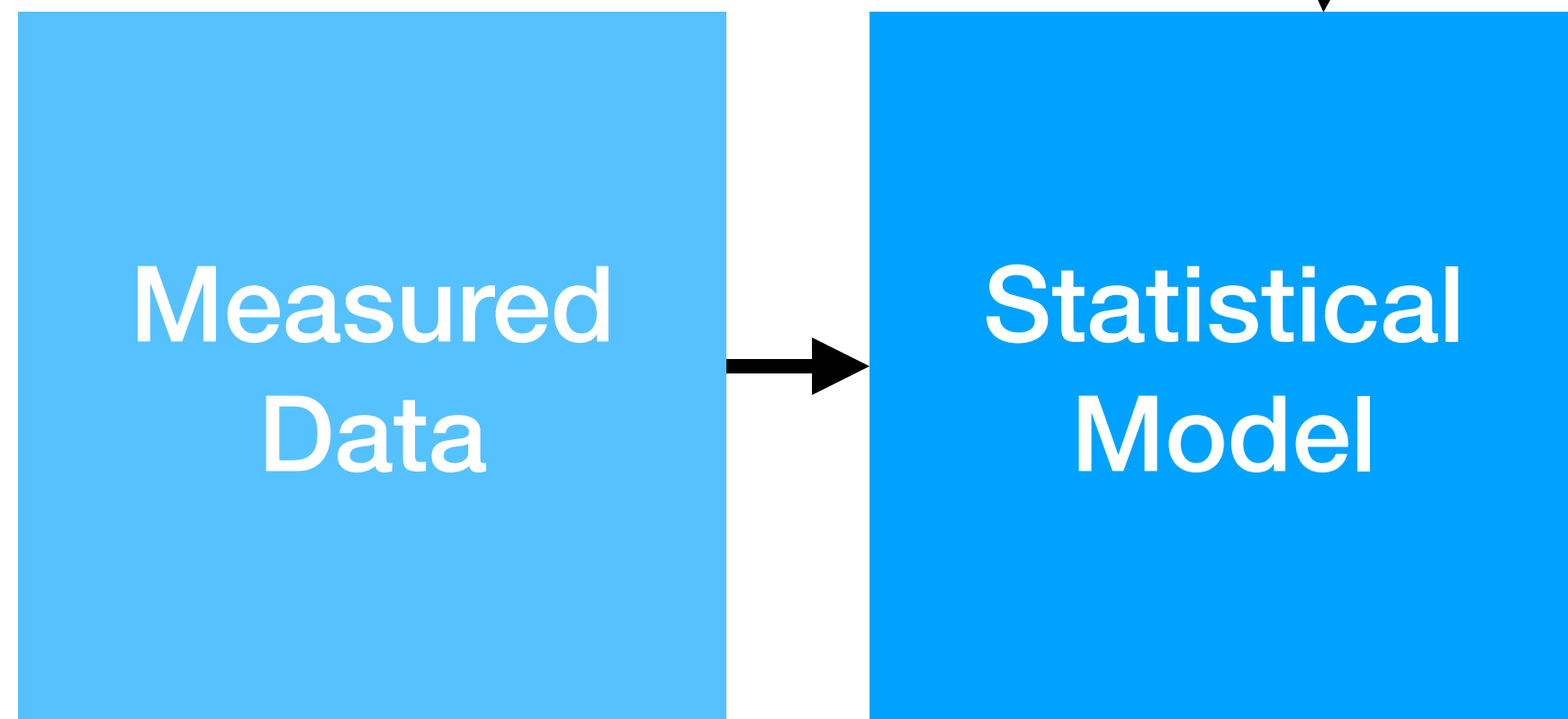




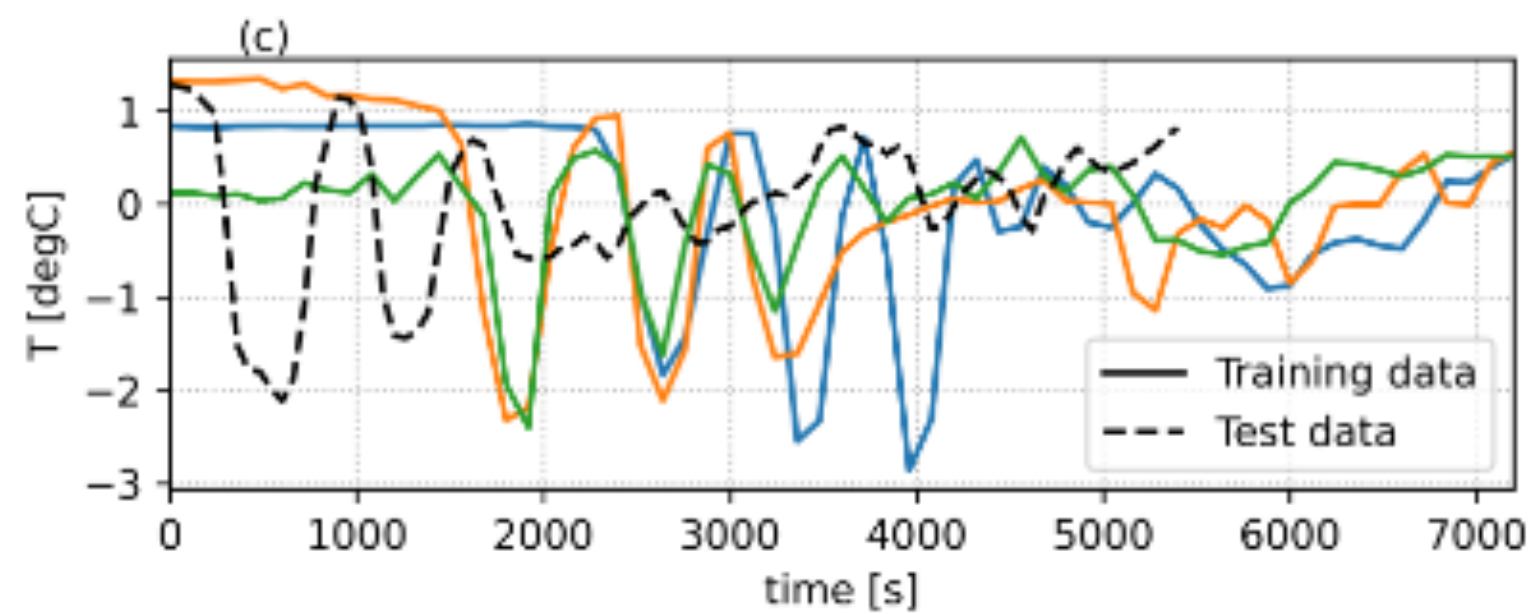
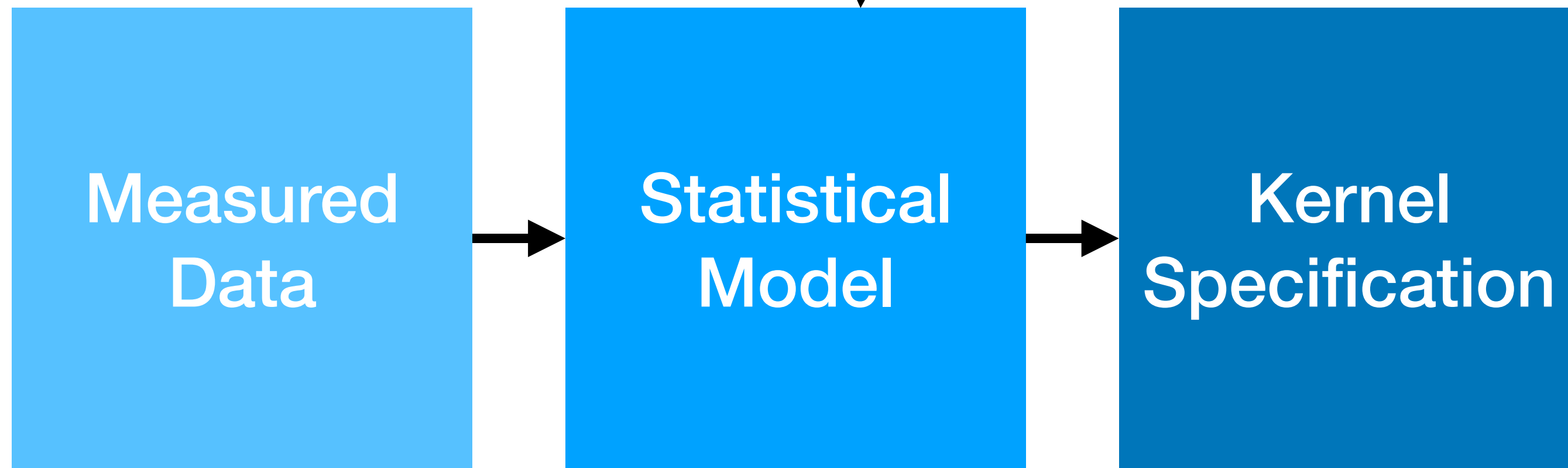
Measured
Data



$$\text{GP}(0, k(\tau; \theta))$$



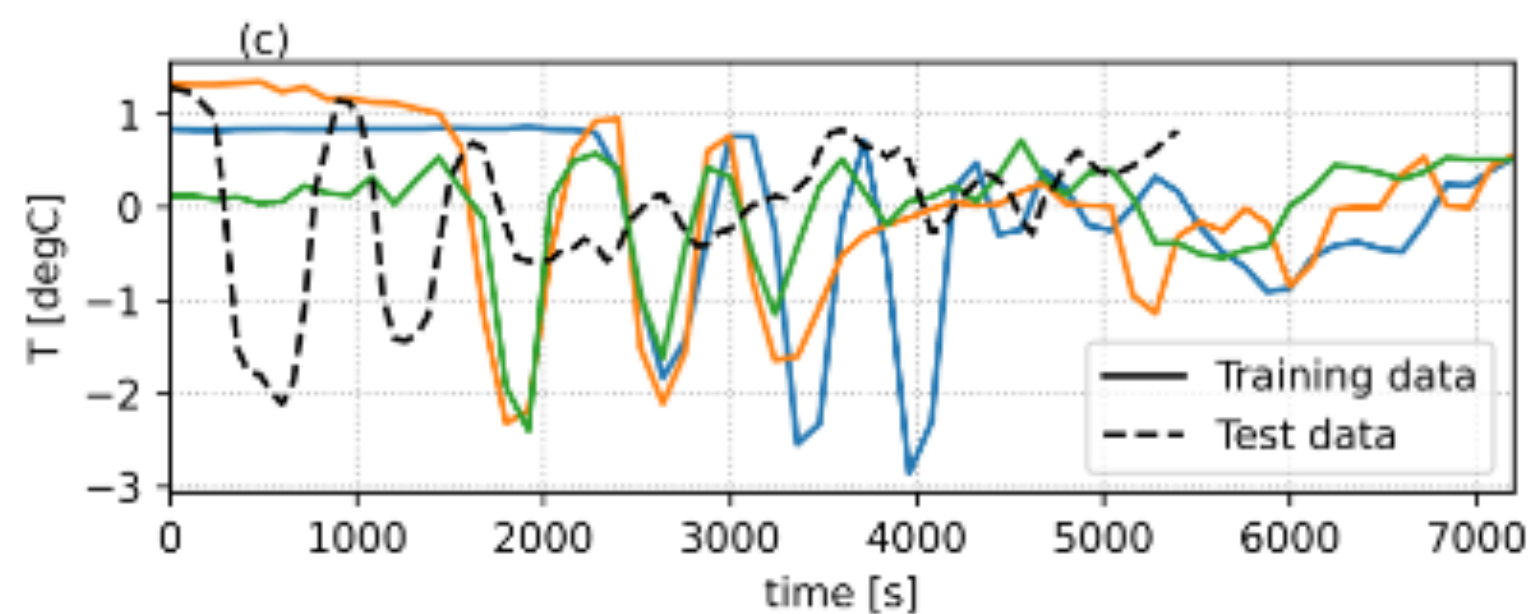
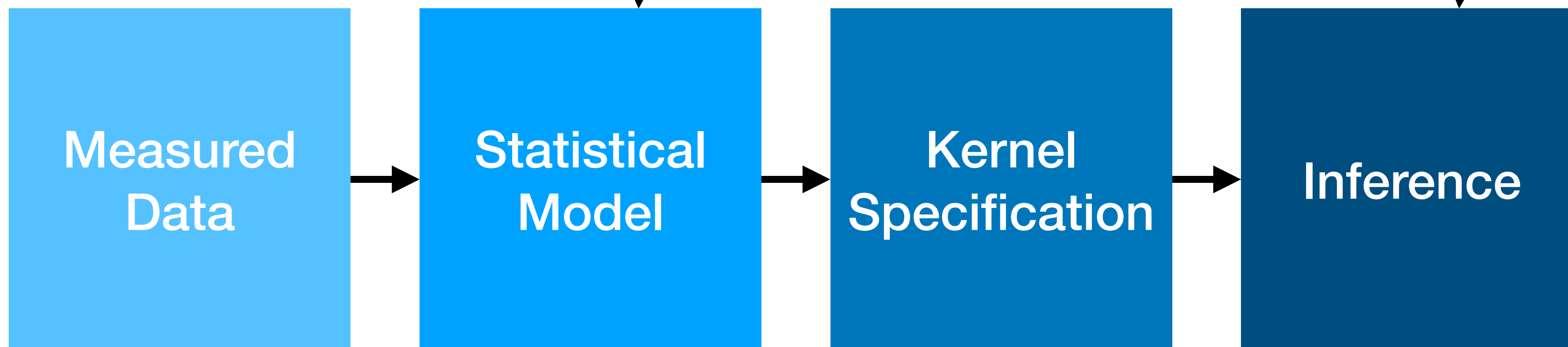
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$$k_{\text{NLIW}}(\tau; \theta)$$



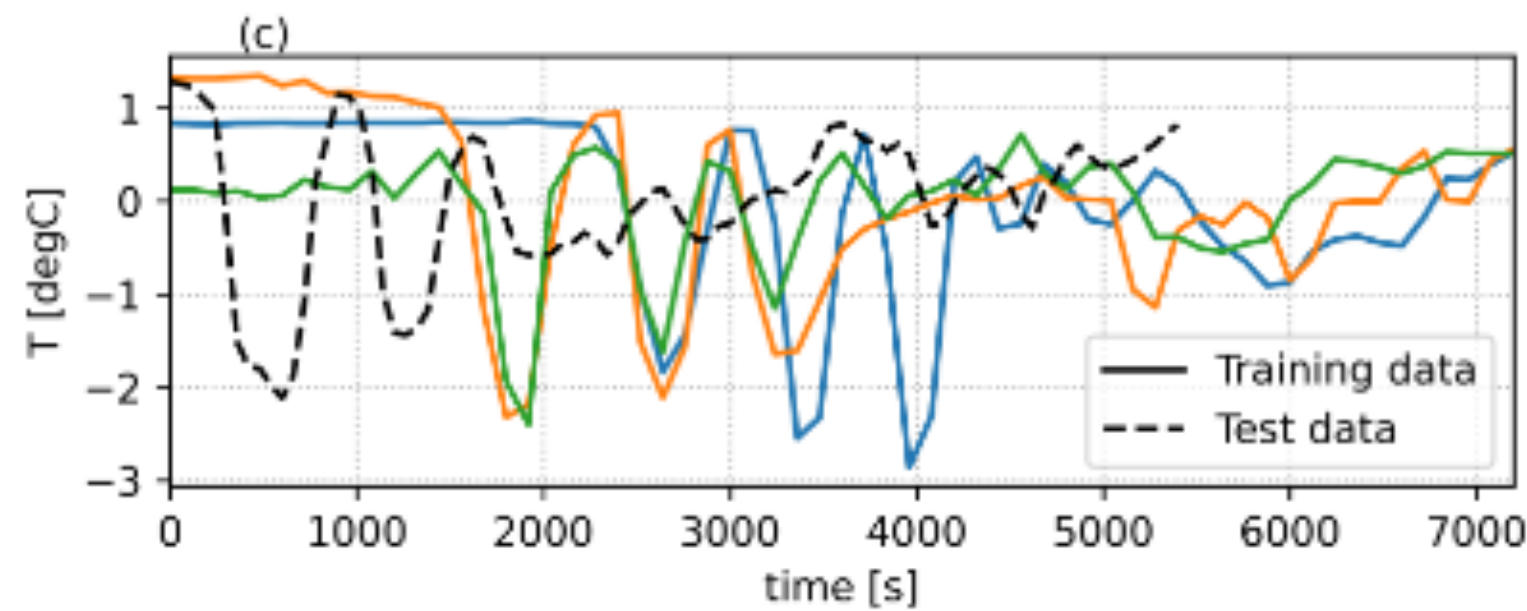
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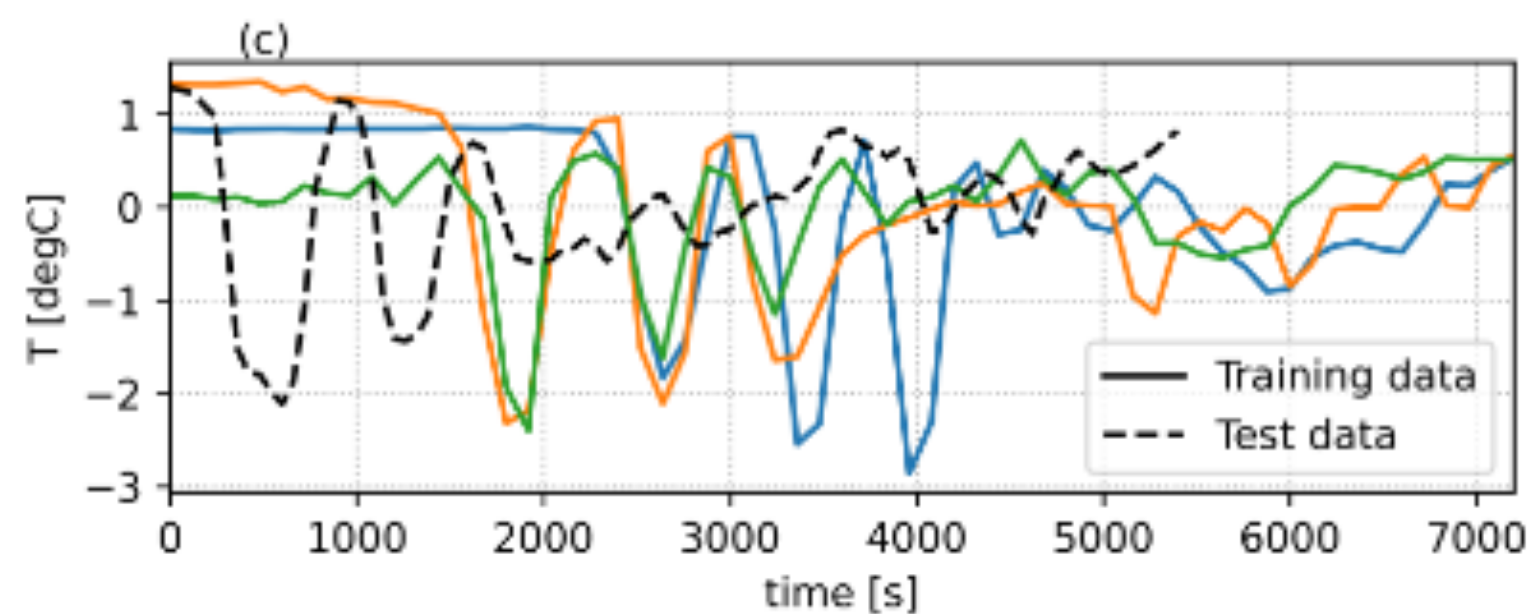
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$$k_{\text{NLIW}}(\tau; \theta)$$

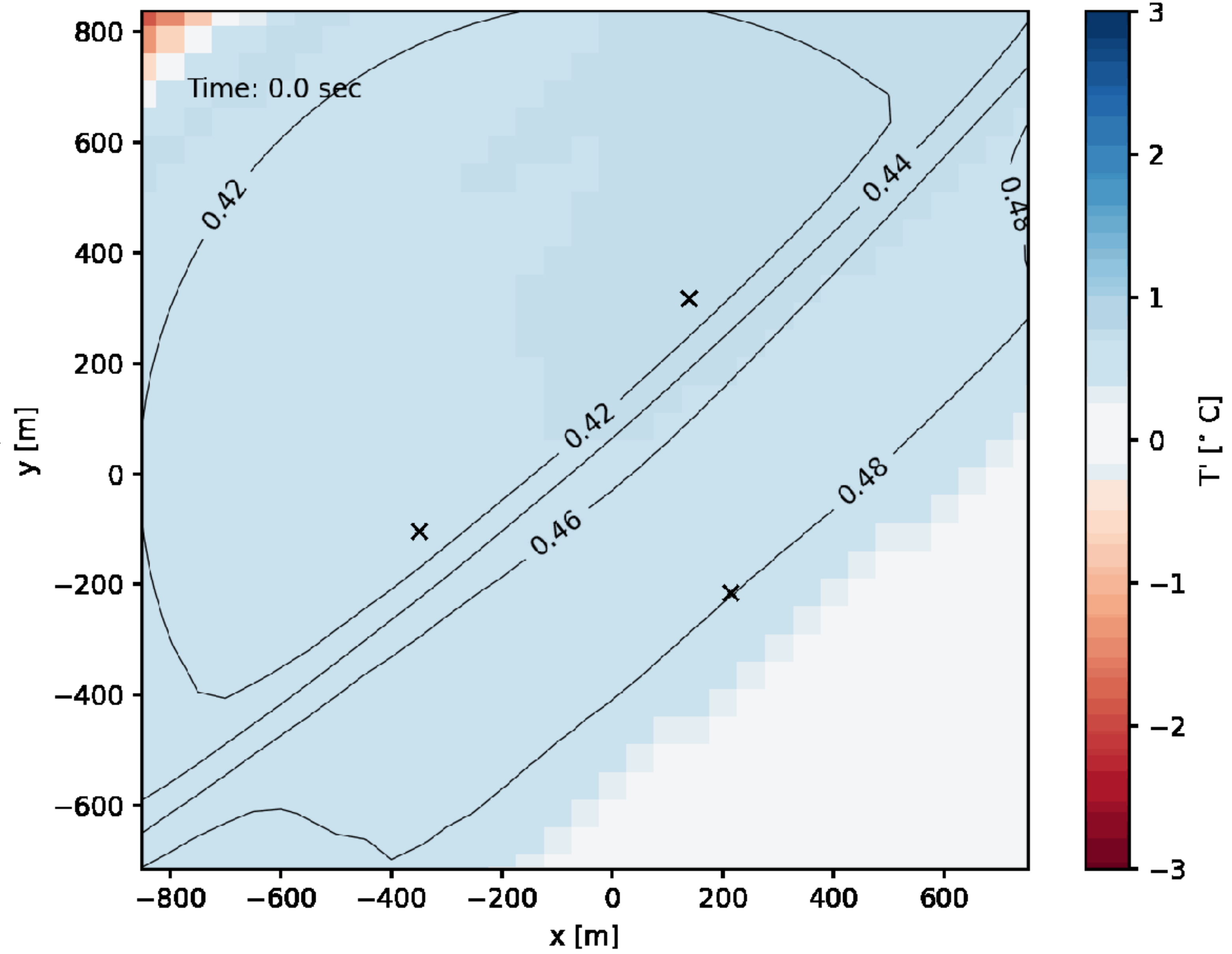


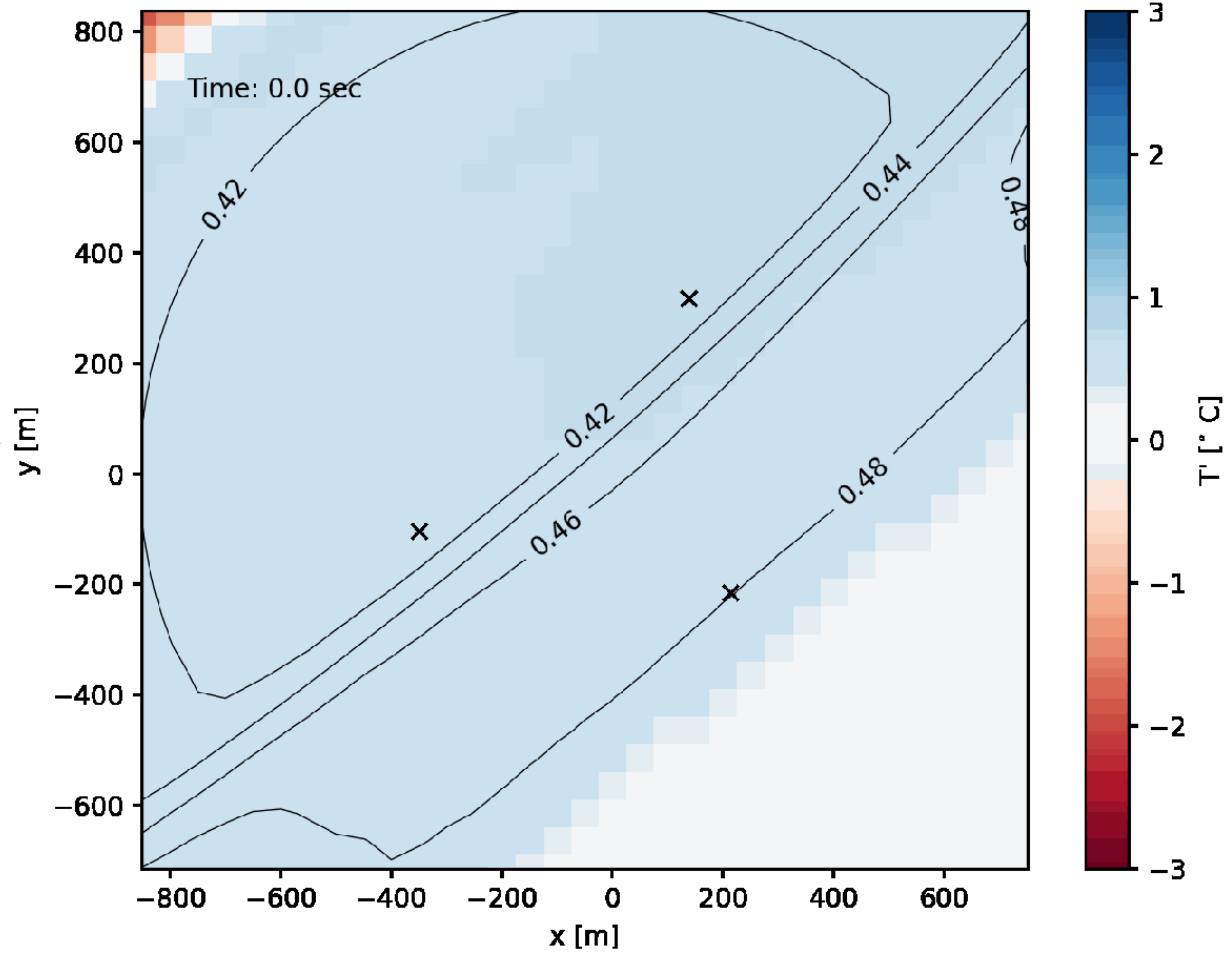
$$GP(0, k(\tau; \theta))$$



$$k_{\text{NLIW}}(\tau; \theta)$$







Where to from here

- Characterise field profiles of NLIWs
- Automated detection of NLIW events from the background process
- Optimise code to run in real time for operations
- Include parameters to model NLIW curvature (only detectable by larger arrays)
- Test on other arrays and for longer periods of time (will require some computational tricks)
- Extend to moorings that observe currents through depth



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- *gptide* code available at github.com/TIDE-ITRH/gptide
- *gptide* tutorials available at gptide.readthedocs.io
- Email methodological queries to lachlan.astfalck@uwa.edu.au
- Email software queries to andrew.zulberti@uwa.edu.au
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