

Status KNM I

Siëbren de Haan

NearRealTime

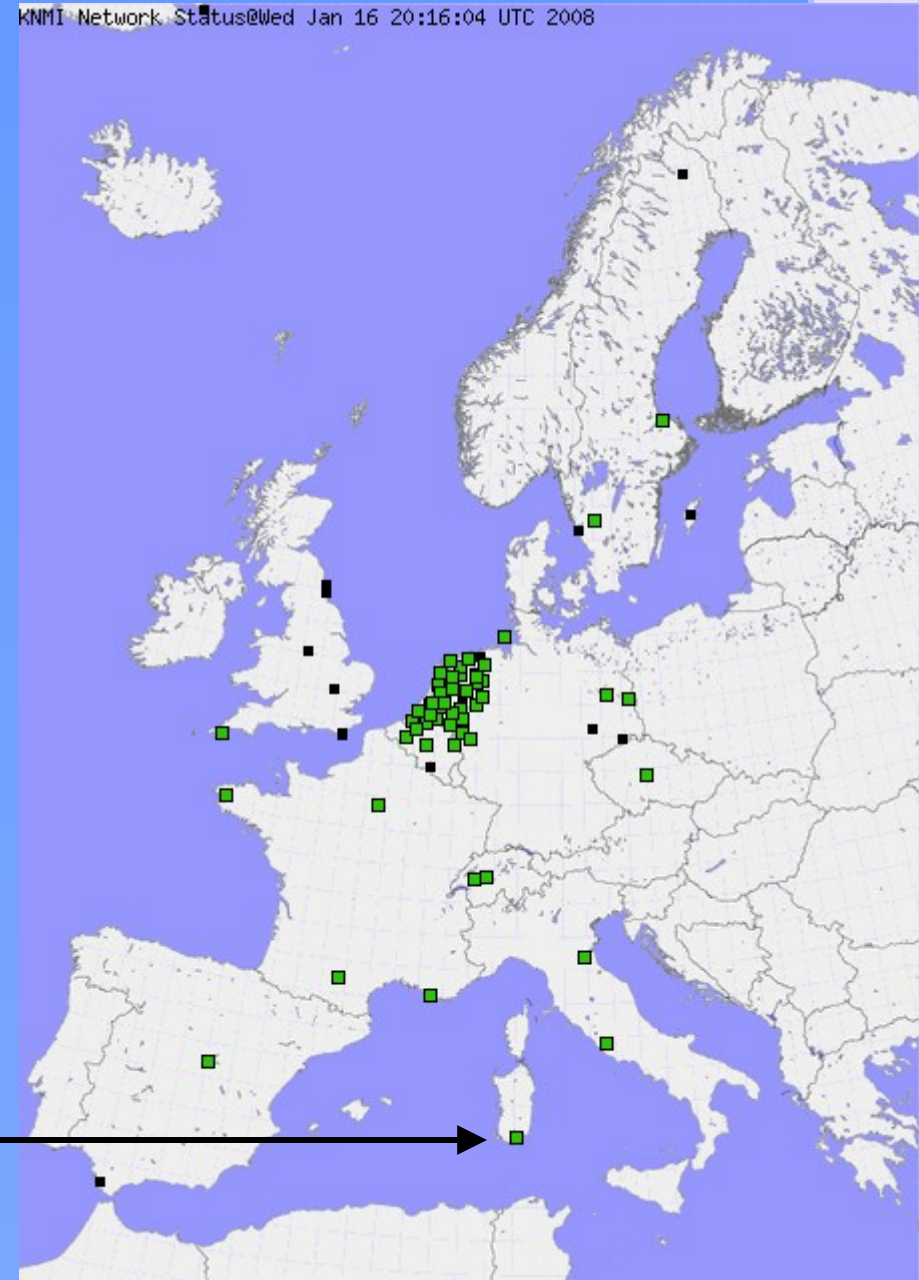
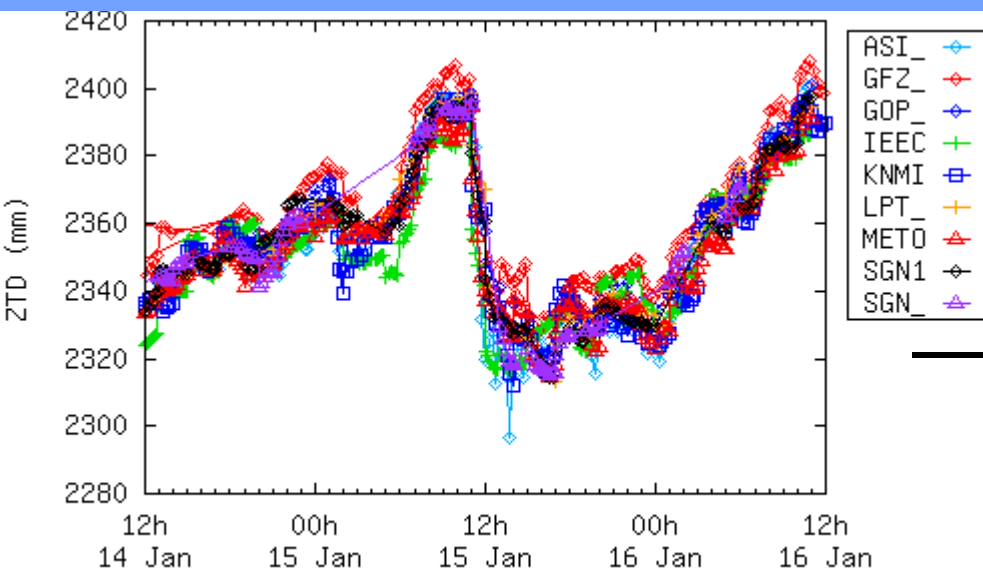
Hourly

NL :Kadaster

GB :Ordnance Survey

EUREF

Available within 40m after
last observation





RealTime Water

Every 15 minutes

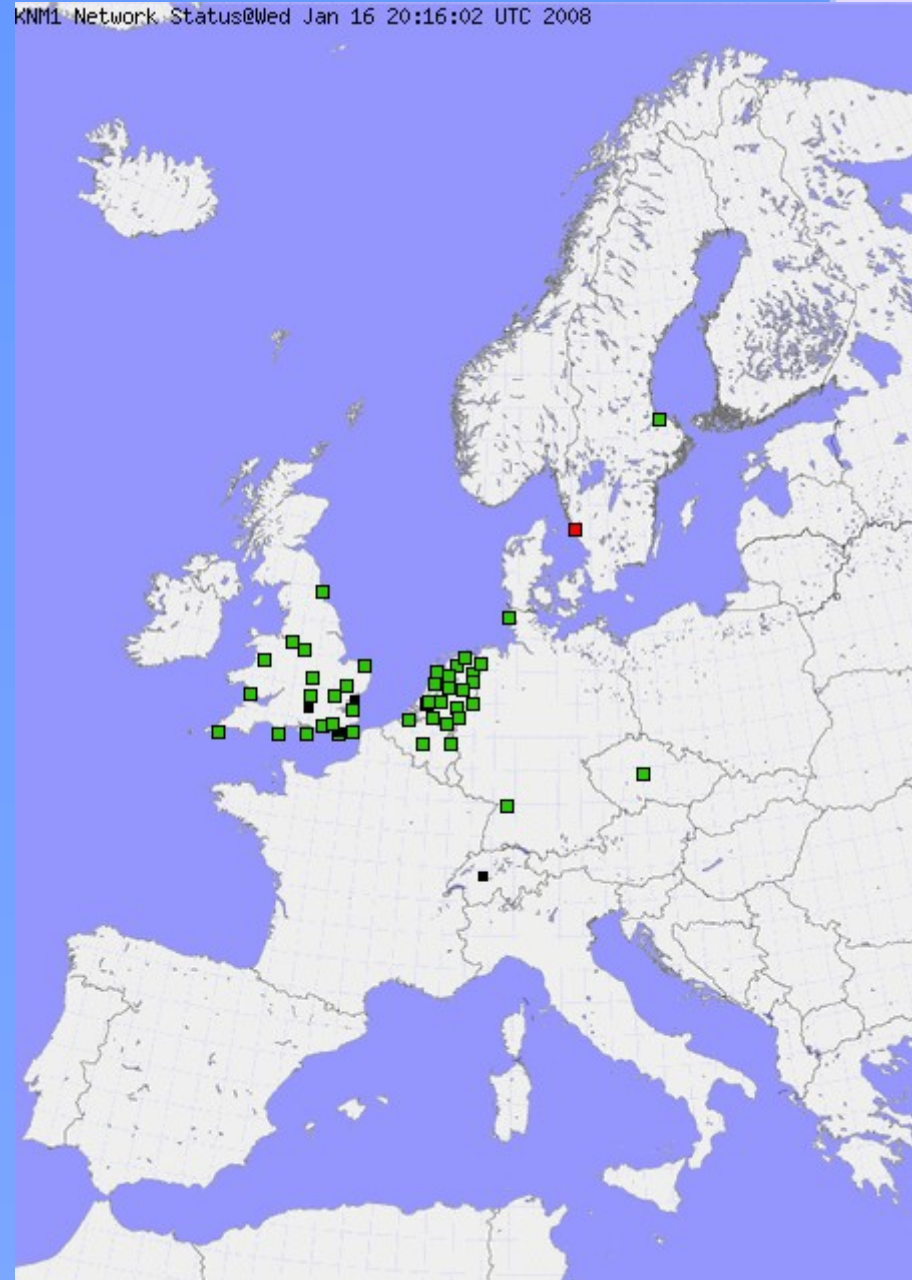
NL :Kadaster

GB :Ordnance Survey

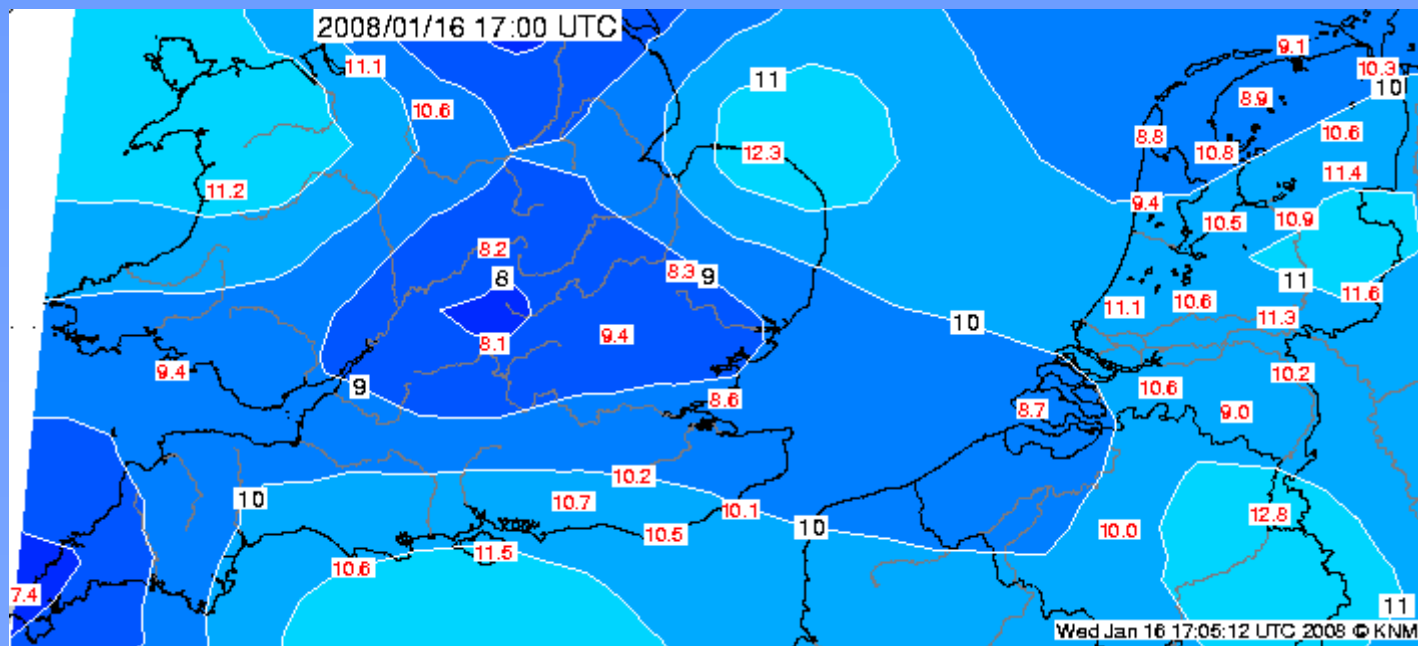
NTRIP

Available within 5 min.

Hourly upload to DB



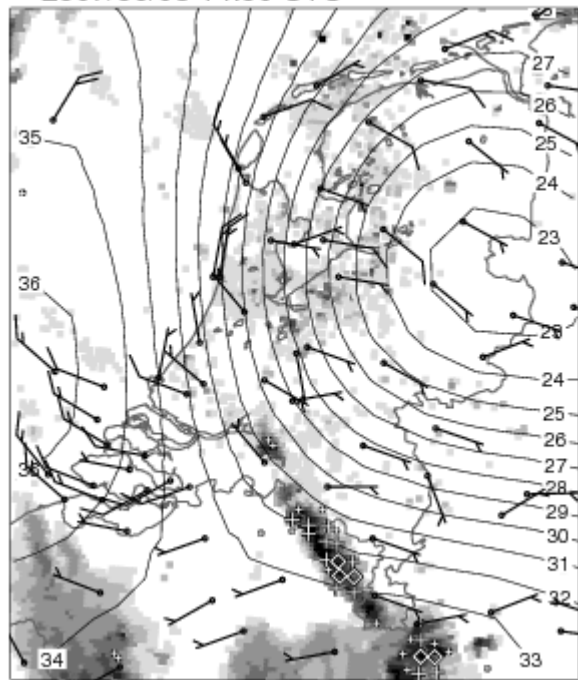
Two dimensional W V map every 15 min.



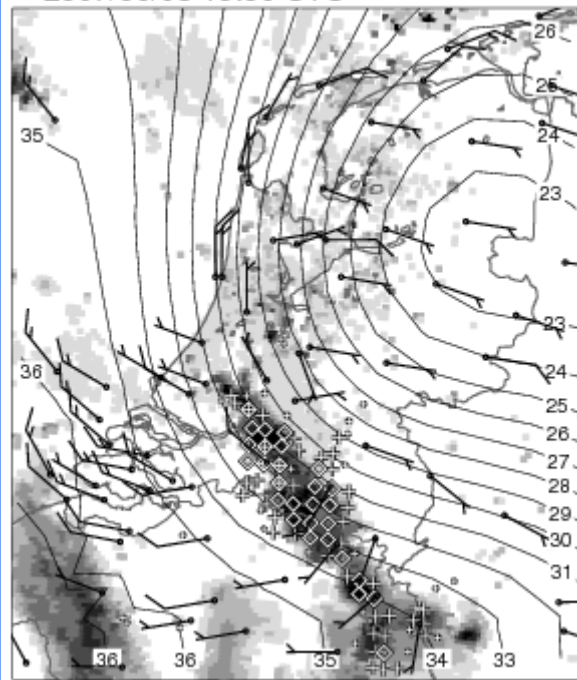
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Case studies

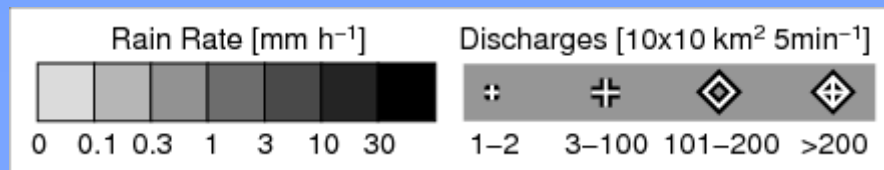
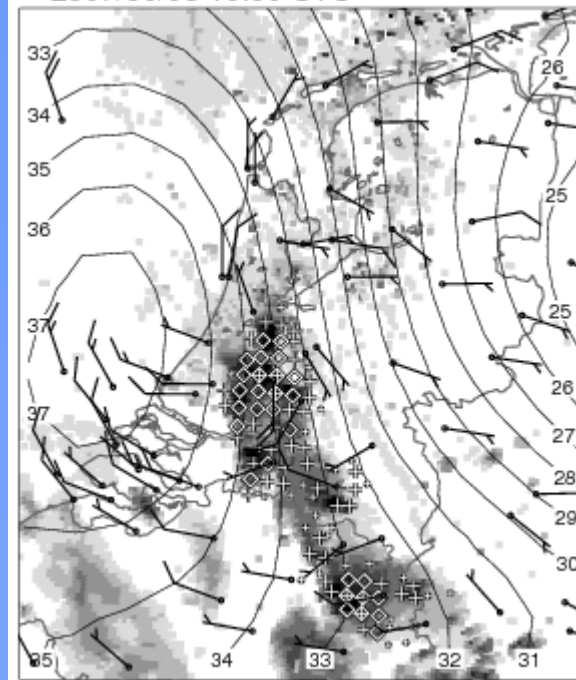
2007/06/08 14:00 UTC



2007/06/08 15:00 UTC



2007/06/08 16:00 UTC



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17-1-2008

E-G VAP plenary meeting

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Assimilation GPS ZTD

Test during summer

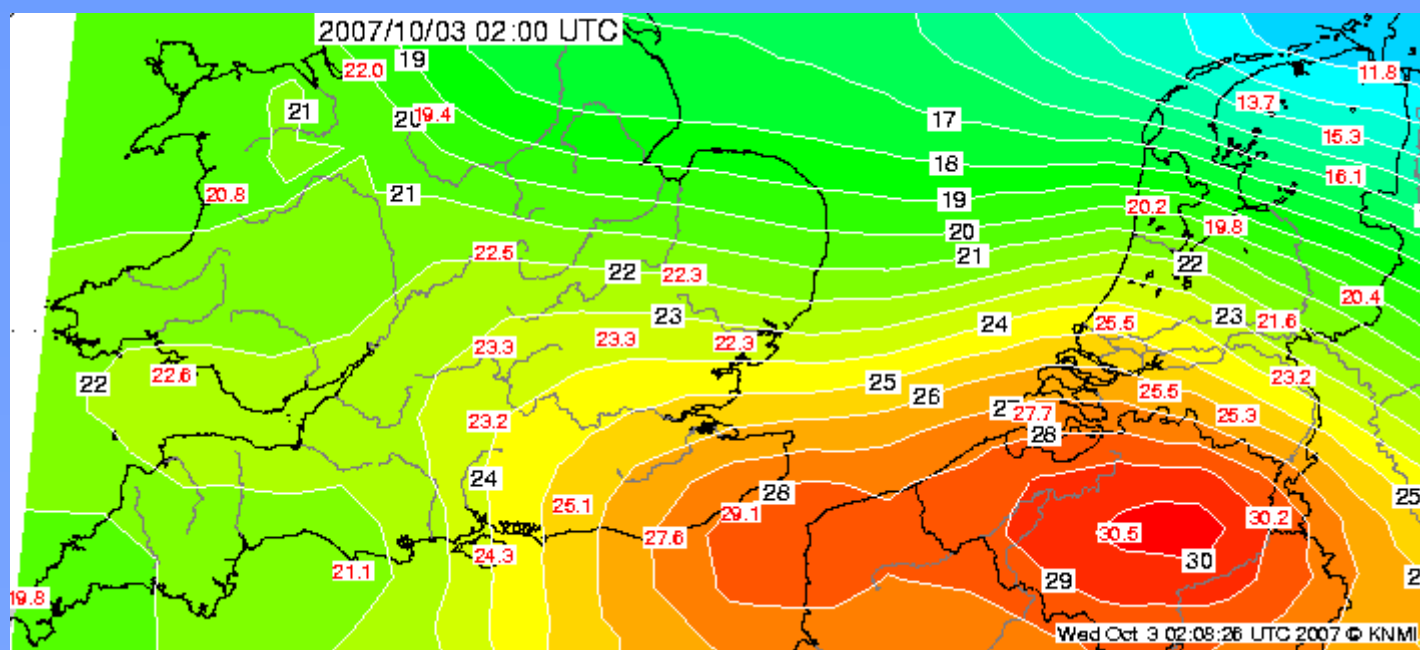
Pre-operational runs since last week (6 Nov.)

Same grid (H 11 km)

Every 3 hours

(Still) waiting for statistics

Thank you





17-1-2008

E-G VAP plenary meeting

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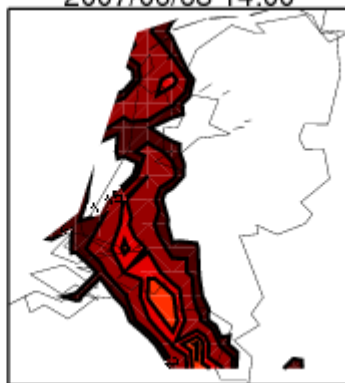
Integrated Moisture Flux Convergence

2007/06/08 12:00

2007/06/08 13:00

2007/06/08 14:00

2007/06/08 15:00

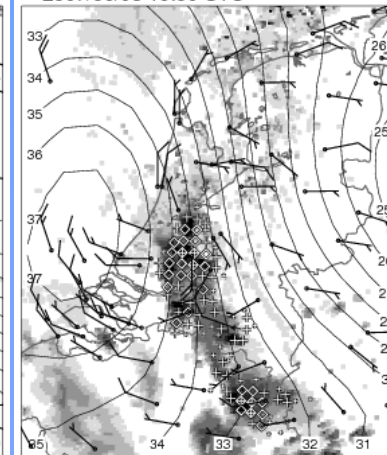
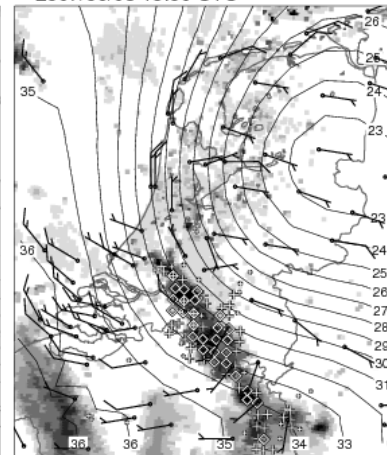
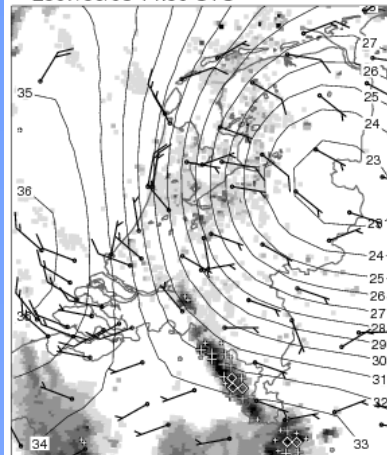


10m wind
GPS WV

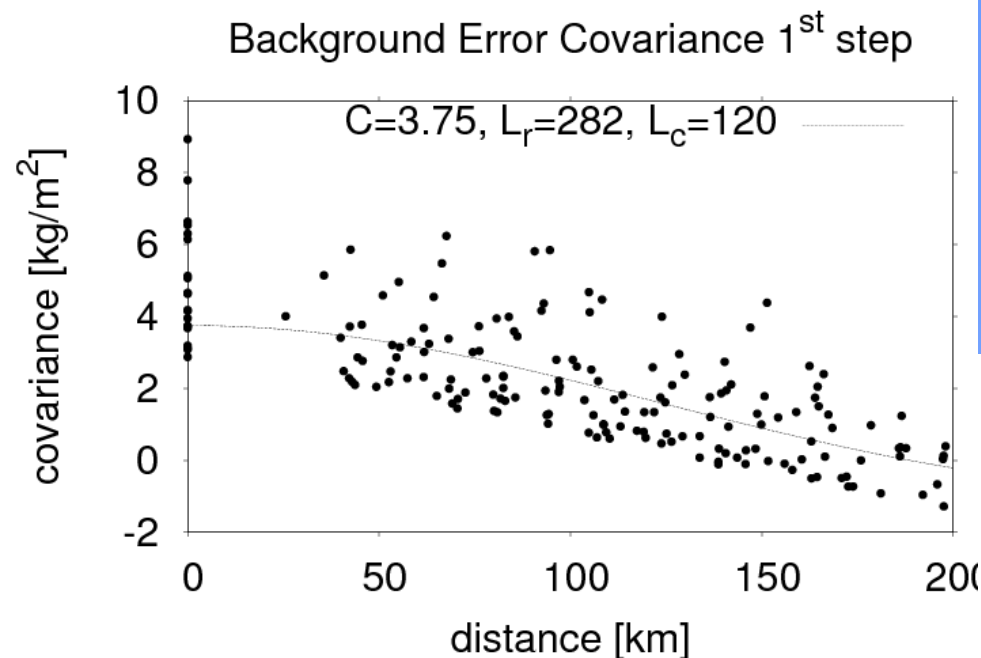
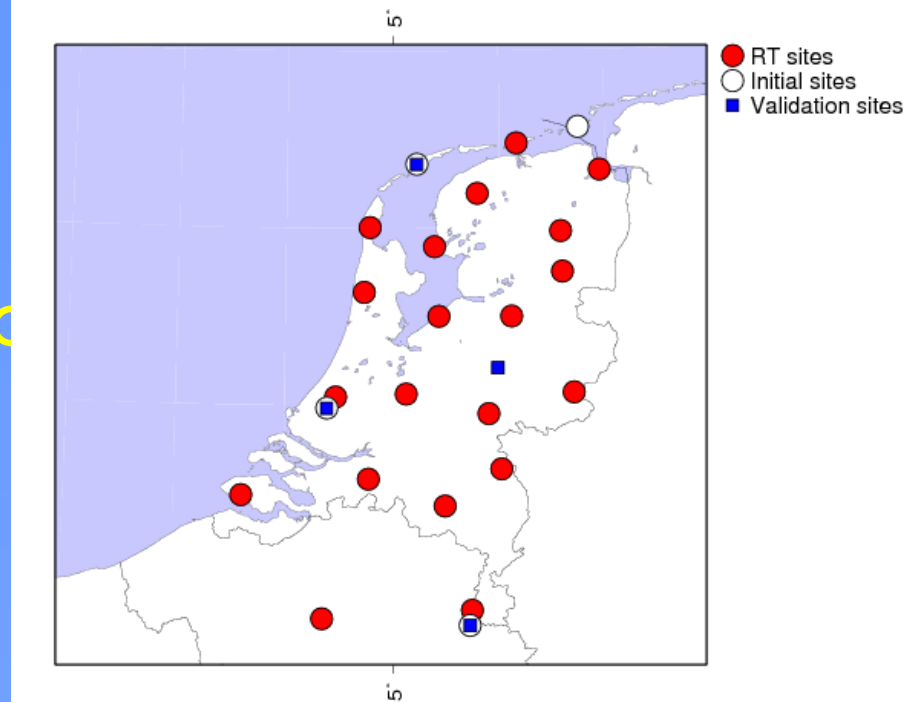
2007/06/08 14:00 UTC

2007/06/08 15:00 UTC

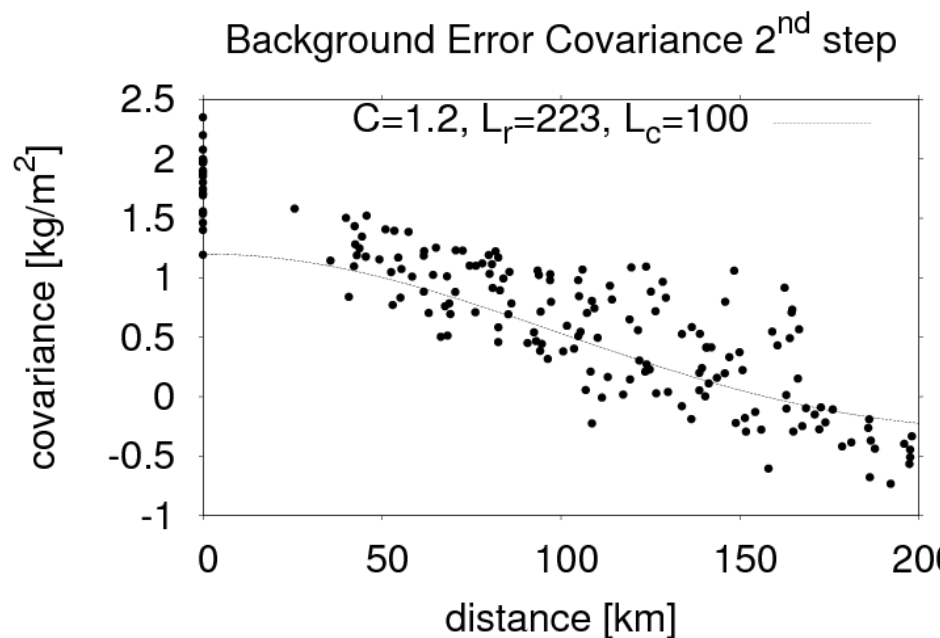
2007/06/08 16:00 UTC



Background Covariance



$$COV_{BG} = C \exp(-r^2/L_r^2) \cos(r/L_c)$$



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Assimilation => Knowledge error covariances

Observation : assume no correlation

Background

WV not general atmospheric parameter

The observational Hollingworth–Lonnberg method

2 steps

- 1) Estimate BG-Cov using mean WV of 4 (not RT) sites
and create AN (00'') and RT observation
- 2) Estimate BG-Covariance using BG from 1) and RT observations 15 minutes later
[ie. BG = AN (00'') and OBS = RT (+15'')]

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