

Title: **WP5: NRT at TUG – Status and Plans**

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Status of NRT implementation

- NRT is implemented according to D5.1 using L1B data and final GPS products
- GRACE time series starting from 2006 is currently being processed
- Primary focus:
 - Impact on solutions of NRT strategy compared to post processing
 - Finding software bugs and generally improve robustness
- Adaption of kinematic orbit processing to rapid products

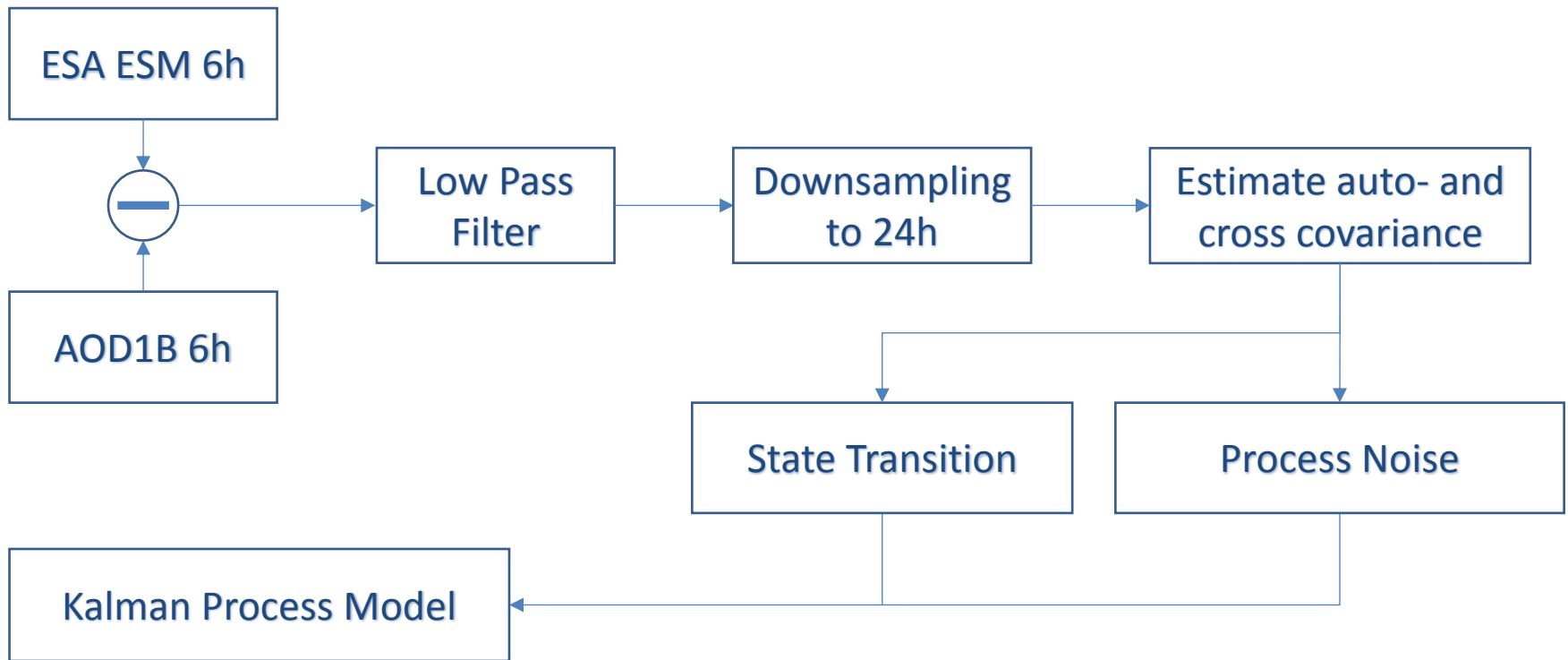
Kalman Solutions: Basic Concept at TUG

- State transition is based on least squares prediction

$$\mathbf{x}_t = \mathbf{B}\mathbf{x}_{t-1} + \mathbf{w} \quad \mathbf{B} = \Sigma_{\Delta}\Sigma^{-1}$$

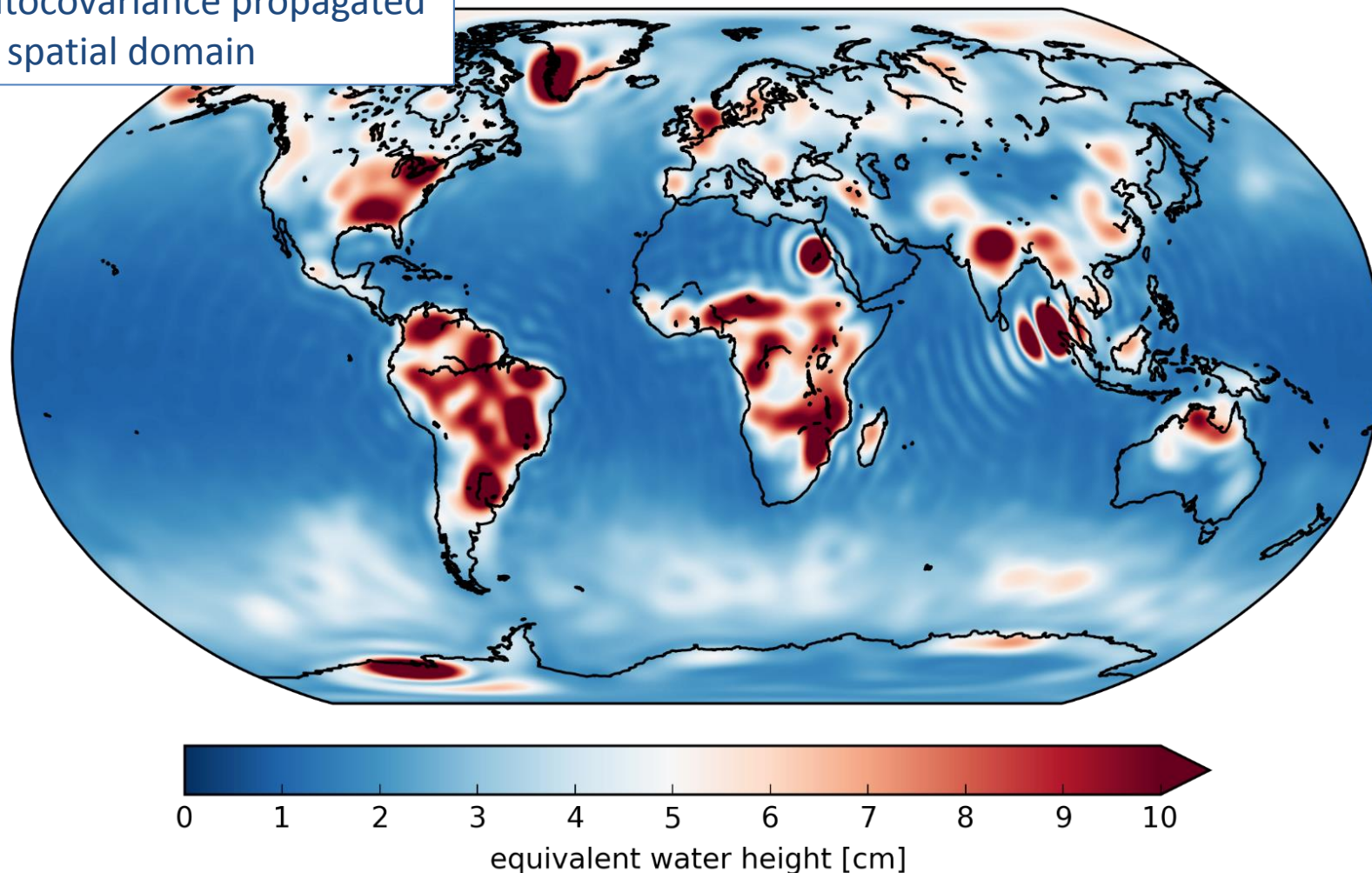
- Auto- and cross covariance can be derived in multiple ways:
 - assume the errors will be proportional to the amplitude of the signal
 - Use ensemble run differences
 - ...?
- Currently, the model differences of ESA ESM and AOD are being investigated

Process Model Derivation (1)

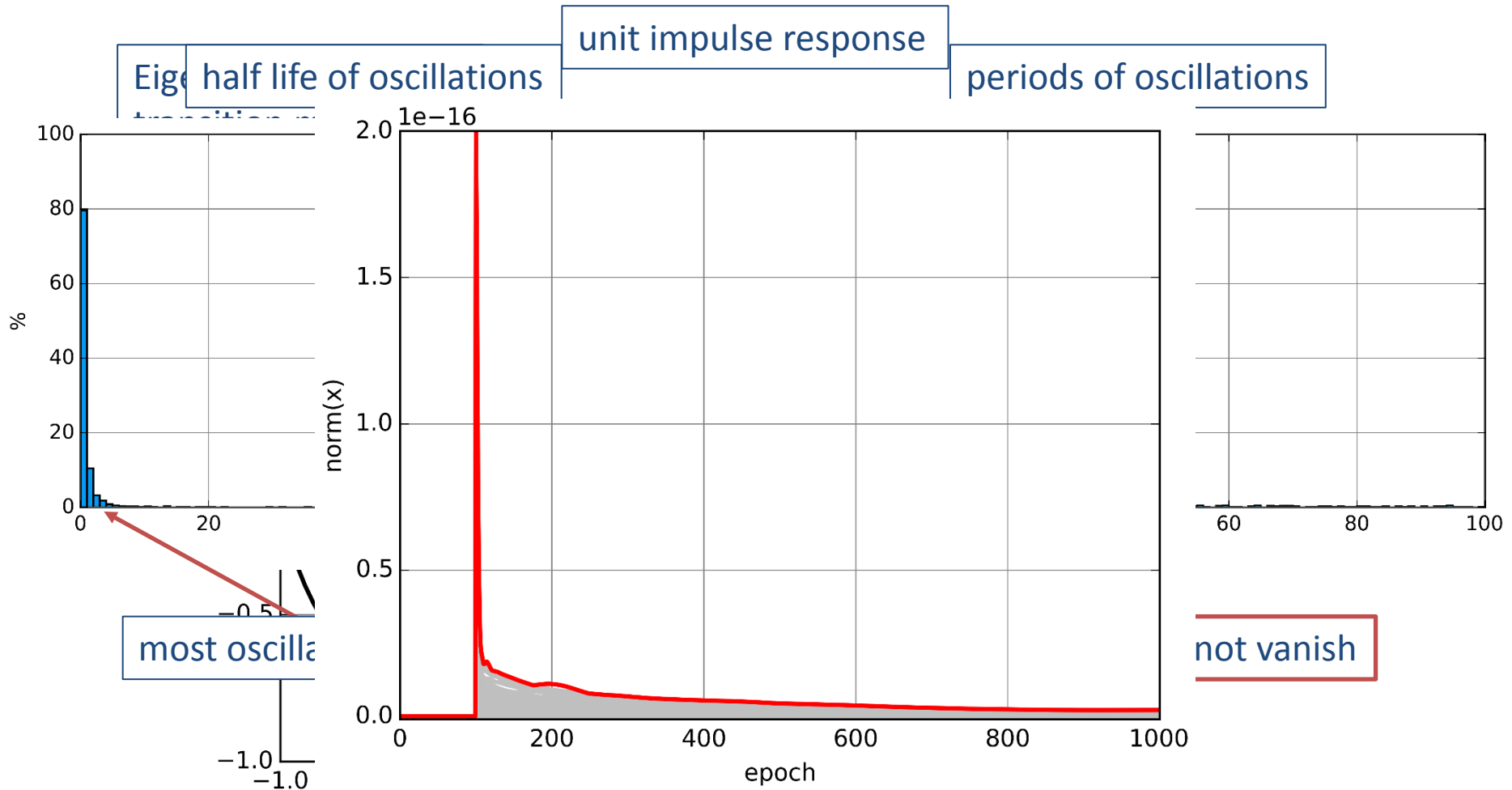


Process Model Derivation (2)

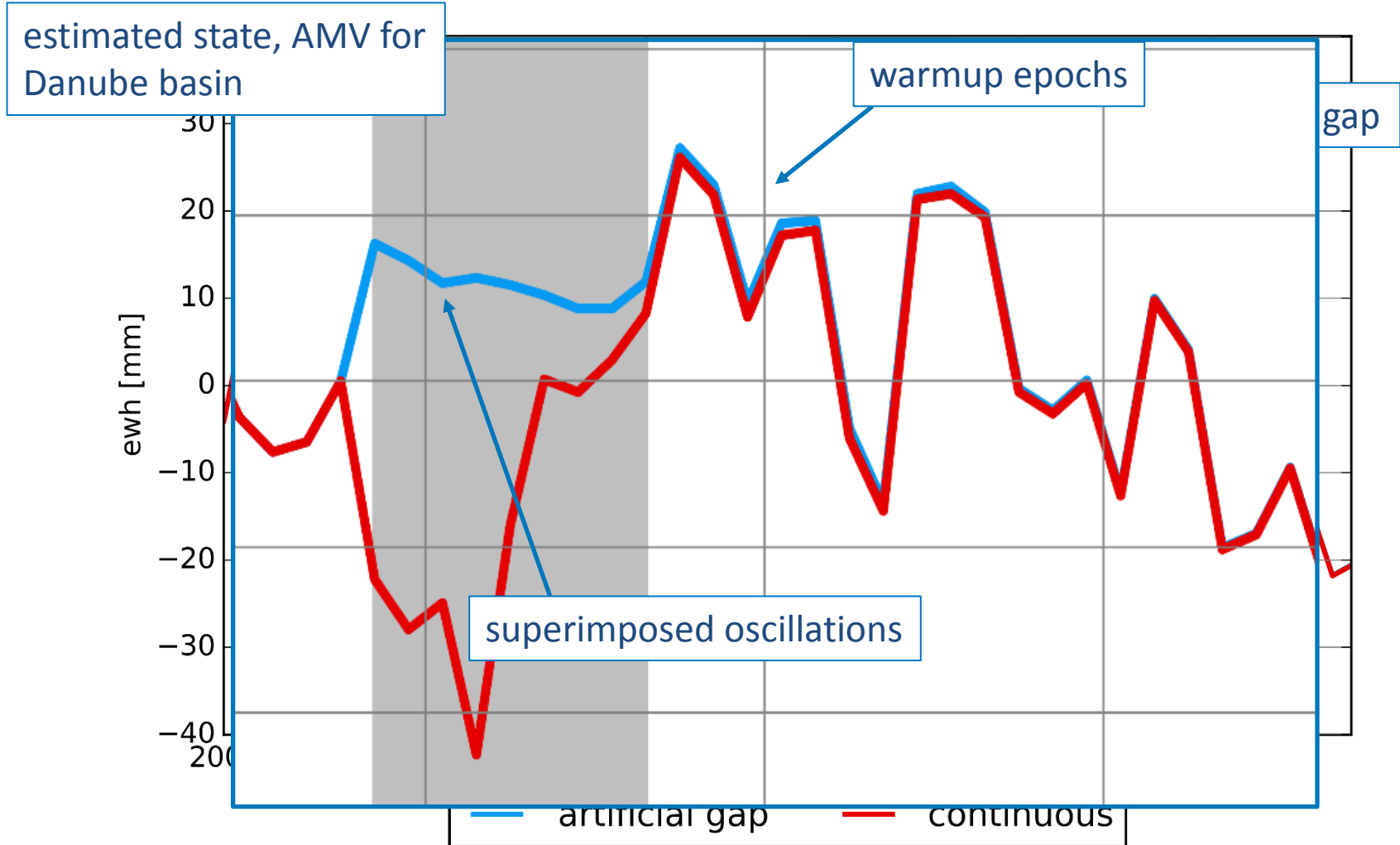
autocovariance propagated
to spatial domain



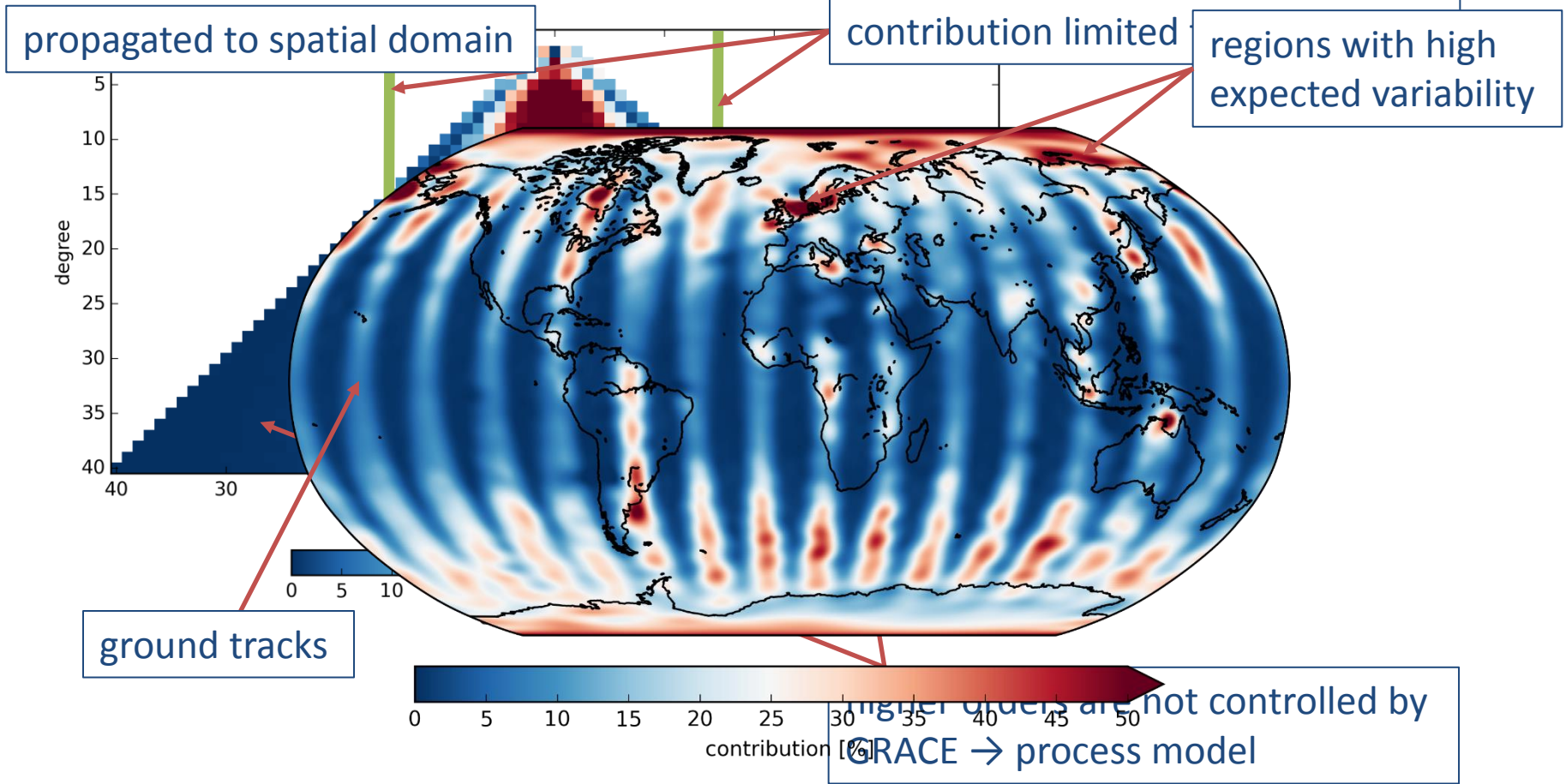
Process Model Properties (1)



Process Model Properties (2)



Contribution of GRACE to Updated State



Plans and Outlook

- Finalizing software framework
- Process model tuning
 - Handling of long term correlations in data gaps
 - Introducing new WGHM daily time series (maybe?)
- M7- : Reprocessing of time series using rapid GPS products
 - Improvement of kinematic orbit processing
 - T5.2: data basis for hydrological service (T6.1 & T6.2)
- M7- : Working towards (provisional) service operations resulting in D5.2

Items of Discussion

- During the development of the NRT Draft Concept (D5.1) some interesting points came up:
 - Dependence of the daily solutions of the models used to derive state transition and process noise matrix
 - Impact of constraint on the daily solutions