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TITLE: OBSERVATIONS OF TORNADOES AND WALL CLOUDS WITH A
PORTABLE FM-CW DOPPLER RADAR: 1989 - 1990 RESULTS

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OBSERVATIONS OF TORNADOES AND WALL CLOUDS WITH A PORTABLE FM-CW DOPPLER RADAR: 1989-1990 RESULTS

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1. INTRODUCTION

Little is known about the wind field in tornadoes near the ground. Photogrammetric analysis (Golden and Purcell 1977, 1978; Hoecker 1960) of tornadic debris clouds does not reveal the internal structure of the tornado vortex. Estimates of wind speeds based on damage analysis often contain large uncertainties (Dorwell and Burgess 1988). Direct measurements made by an instrument placed in the path of a tornado are extremely difficult to obtain (Bluestein 1983a; Bluestein 1983b; Burgess et al. 1985). Several measurements of tornadic wind fields near cloud-base level have been made when supercell tornadoes have formed on rare occasion near the National Severe Storms Laboratory's Doppler radar (Zrnica and Doviak 1975; Zrnica et al. 1977; Zrnica and Istok 1980; Zrnica et al. 1985). Measurements of the wind field below cloud base have been made in non-supercell tornadoes in Colorado (Roberts and Wilson 1989; Wakimoto and Martner 1989; Wakimoto and Wilson 1989).

Little is also known about how tornadoes form within the mesocyclone of a supercell thunderstorm. Although it is believed that solenoidally generated horizontal vorticity along the forward flank downdraft is tilted and stretched under the main updraft to increase vorticity at the surface (Klemp and Rotunno 1983), it is not known how the smaller-scale tornado forms. Actual measurements of the sub-cloud base wind field and the relationship between the wind field and sub-storm scale features such as the wall cloud, tail cloud, and laminar inflow bands are lacking.

The purpose of this paper is to report on our progress using a portable, 1 W, FM (frequency modulated)-CW (continuous wave) Doppler radar developed at the Los Alamos National Laboratory (LANL), to make measurements of the wind field in tornadoes and wall clouds along with simultaneous visual documentation. Results using a CW version of the radar in 1987-1988 are given in Bluestein and Unruh (1989).

2. METHODOLOGY

Our field experiments were held during April, May, and June in 1989 and 1990. Our chase vehicles were vans carrying four to six crew members. In addition to the radar, we also carried along a barometer, a psychrometer, video camera recorders, conventional photographic equipment, and a portable radiosonde unit (Bluestein et al. 1988). Sondes were released when possible to obtain thermodynamic soundings in the storms' environment.

The radar was modified to have FM-CW capability prior to the 1989 season. The theory of the FM-CW radar and its signal processing is detailed in Strauch (1976). The radar sends out a continuous signal, whose frequency is swept linearly upward and reset, periodically. The sweep repetition frequency (15.575 kHz) of the LANL radar, which operates at 3 cm, is controlled by the sweep repetition frequency of a VCR, which records the data. The sweep repetition frequency of an FM-CW radar is analogous to the pulse-repetition frequency of a pulsed Doppler radar. For the aforementioned parameters and a sweep width of 1.9 MHz, the maximum unambiguous range of the radar is 5 km; the maximum unambiguous velocity is ± 115 m/s; the range resolution is 78 m. Since the half-power beamwidth of the antennas is 5 deg, the resolution volume at 2.5 km is 218 m X 218 m X 78 m.

The radar can be mounted on its tripod by two crew members and set up for operation in several minutes. The radar's umbilical cord is connected to batteries and to the video and audio recorders housed in a carrying case, which can be transported by two crew members (Fig. 1). The brightness of the video camera image must be adjusted manually. The level of the CW signal is monitored on the audio recorder and adjusted manually on the radar unit; the audio recorder's dynamic range is at least 60 db, while the radar's dynamic range is 70 db. In the FM-CW mode the signal quality is monitored on the video screen. The dynamic range of the VCR is only 30-40 db. Overloaded signals appear as unsynchronized, torn-up looking frames. Considerable qualitative information can be obtained from visual examination of video frames. "Good" signals appear as tilted lines. The range of the target is inversely proportional to the spacing between lines; the velocity of the target is given by the slope and sense of tilt of the lines. Target volumes in which there is complex wind structure appear as criss-crossed hatched lines. Range folding appears as an abrupt change in the slope of the lines. Further interpretation of the video picture will be given elsewhere.

The FM-CW radar data (i.e., the video signals resulting from mixing the transmitted FM-CW signal with the backscattered signal) are recorded on videotape, and voice documentation is recorded on audio tape and on the audio channels of the videotape. When the radar operates in the CW mode, actual bore-sighted video of the cloud features and tornado are recorded on video tape, while radar data are recorded on the stereo audio tape and on the stereo audio

[illegible]

• The above Theorem can be extended as follows:
• Theorem 2.1. Let f and g be two functions defined on $[a, b]$ such that f is continuous and g is differentiable on $[a, b]$. Then

As a result, the video frame of the data is digitized at a resolution of 128 data points (256 per line times 128 lines) to produce 204 lines per frame. The data are then stored in a range of data frequencies (up to 100 Hz) and a number of lines (up to 128) digitized at 128 data points per line. This is done by compressing the data into a range of data frequencies (up to 100 Hz) and a number of lines (up to 128) digitized at 128 data points per line. The data are then stored in a range of data frequencies (up to 100 Hz) and a number of lines (up to 128) digitized at 128 data points per line.

Figure 1 shows the variation of the range rate with the range rate error. The range rate error is defined as the difference between the true range rate and the estimated range rate. The range rate error is plotted against the range rate error. The range rate error is plotted against the range rate error. The range rate error is plotted against the range rate error.

1. The first step is to identify the problem or question that needs to be answered. This involves understanding the context and the specific requirements of the task.

... get a frequency as high as the highest ...

As a result, the antenna array used horizontally only, which is shown in the CW mode so that vertical beam steering is achieved by the feed network, the beam-steering range is

measuring. It is necessary to keep the antenna close to the surface of the object being measured in order to collect maximum energy for analysis in the CW mode. We used a 100-MHz CW signal of approximately 3 mW (10 dBm) to excite the well. As on the resonator and alternate between CW and pulsed CW mode. Various authors have demonstrated that the resonator is more sensitive to resistance than to the inductive reactance.

Results

The data sets we collected are listed in Table 1. It is relatively easy to obtain data sets on well-tended populations. It was found that there was a strong reflectivity problem associated with the macrobiological data sets, especially for the fish data.

[illegible]

TABLE 1: Significant Data Sets

Date	Approximate Location	Event	Comments
13 May 1989	Hodges, Texas	tornado	data contaminated
14 May 1989	Coahoma, Texas	wall cloud	data contaminated
6 June 1989	Floydada, Texas	wall cloud	
23 April 1990	Turkey, Texas	wall cloud	weak signal
24 April 1990	McLean, Texas	wall cloud, funnel cloud	
24 April 1990	Kelton, Texas	wall cloud	
15 May 1990	Calumet, Oklahoma	wall cloud	
29 May 1990	Old Glory, Texas	wall cloud	
31 May 1990	Spearman, Texas	tornado, wall cloud	
15 June 1990	Liebethal, Kansas	wall cloud, funnel cloud	

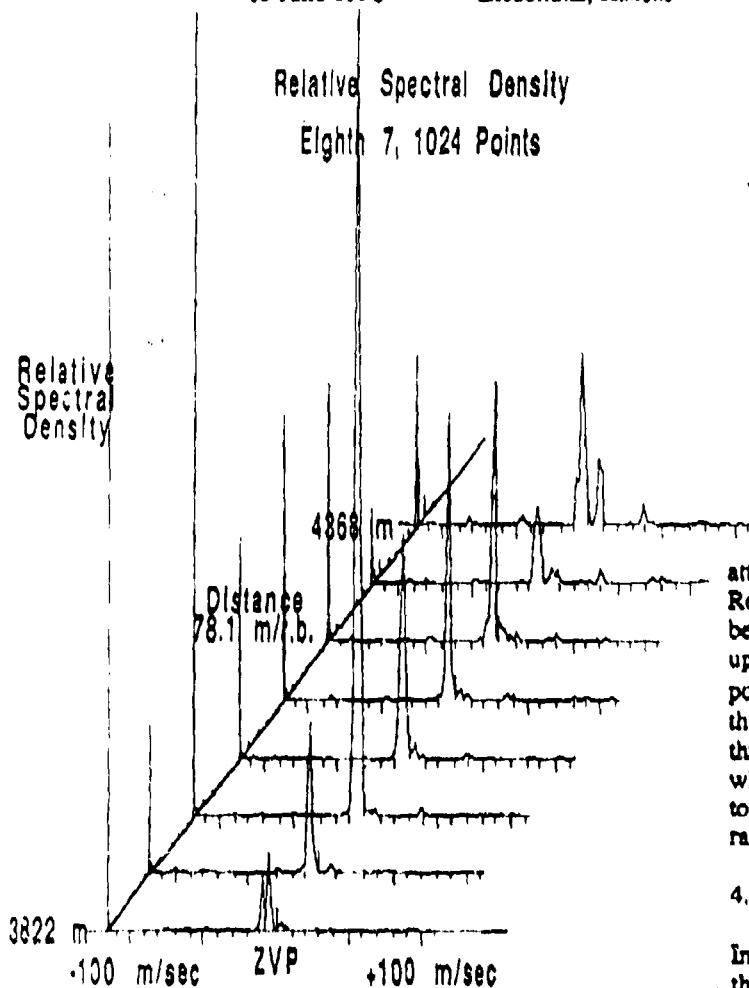


Fig. 2: Relative spectral density as a function of Doppler velocity in a wall-cloud associated with an occluded mesocyclone on 6 June 1989 in Floydada, Texas; for range bins between 3.8 km and 4.4 km away from the radar, looking towards the wall cloud. In this example the mean flow is towards the radar at speeds of only 10 m/s or less. ZVP is the zero-velocity point. A tornado had dissipated earlier in a previous wall cloud. We are looking at flow from the rear flank downdraft around the circulation.

was 22 km long and as wide as 1.6 km (Steven Cooper, NWS, Amarillo, Texas, personal communication). We were situated within 10 km from the tornado, and may have to correct for range-folded velocities in the FM-CW mode. We made a hasty exit from our location when the wall cloud of the occluded mesocyclone came almost overhead and 6-cm diameter hail began to fall.

There were a number of data sets that we failed to collect, but came close to collecting. On 6 June 1989 we arrived in Plainview, Texas approximately 10-15 minutes too late to record data on a tornado that we observed dissipating ahead of us. We attempted to gather data on a tornado south of Calumet, Oklahoma on 15 May 1990, but the tornado had lifted by the time we set up the radar. On 26 May 1990 we

attempted to collect data on a funnel cloud northwest of El Reno, Oklahoma and on a tornado near Hinton, Oklahoma; it began to rain on both of these occasions as soon as we set up the radar, and consequently we had to move from our positions, which were southeast and east, respectively, of the storms. On 31 May 1990 we observed a tornado moving through Spearman, Texas (this tornado formed in a storm which formed after the one which had produced the F3 tornado); by the time we got close enough to set up the radar, the tornado had dissipated.

4. SUMMARY

In 1989 we had difficulties getting enough experience with the radar, owing to a relatively low number of tornadoes in Oklahoma, our home base of operations. A problem with the radar hardware was identified and corrected. We did obtain a good wall cloud data set which allowed us to experiment with the processing of a real FM-CW data set.

In 1990 we obtained a number of wall cloud data sets and a tornado data set. Results are forthcoming.

Based on our experiences we suggest that the following modifications to the radar system and to our method of operations be made:

- The current maximum unambiguous range of 5 km is a bit too restrictive. The system should be modified so that a longer maximum unambiguous range, at the expense of the

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tornado is greater than 5 km away.

b. An automatic exposure video camera should be substituted for the current manual-exposure camera. We found it difficult and too time consuming to adjust the exposure, especially in bright light.

c. Automatic gain-controls should be used in the video and audio recorders to make it easier for us to prevent overloading the recorded signal. It is more important to obtain high-quality relative reflectivity data than to obtain absolute reflectivity data.

d. Our base of operations should be more mobile. By restricting ourselves mainly to Oklahoma and nearby regions we missed out on several opportunities to collect data elsewhere.

e. Consideration should be given to processing the Doppler spectra in real time, and recording the spectra rather than the actual raw signal. This would allow us to realize the full benefit of the wide dynamic range of the radar, which is necessary in the face of ground clutter.

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