

Response to Reviewer I

This document is color-coded as follows:

- Comments by reviewers are in **blue**.
- Our responses are in **black**.
- Blocks of text that is added to the are in **red**
- **The track-changes can be also seen as a supplement document**

Title, Abstract

1) title Prepositions/articles missing. Also, I don't agree with "integrated" but suggest to use the word "modular". As the visualization has been proven, it is not a perspective "towards", but already production ready, so don't use "towards". I would rephrase the title (this is a mere suggestion) as "Co-processing online visualization: the Regional Earth System RegESM version 1.1".

In the current implementation, the adaptor code between NUOPC cap and ParaView, Catalyst is just a prototype that supports only for regional modelling cases with limited spatial grid support (structured and curvilinear grids). It still needs additional work to be more generic and adaptor code needs to be extended to include support for different mesh types such as unstructured grid for both global and regional applications. These are not implemented yet and needs to design adaptor code carefully for more generic applications. This will be done in the future.

2) abstract Fix language issues, such as: articles, avoid "being" before participles, check use of due to/because of, avoid overly use of "used", avoid "have to", do processes literally "move"? Avoid use of "basically", and many more. It is a major revision task to carefully check each sentence

Abstract section is modified based on your suggestions.

3) abstract Avoid jargon especially in the abstract, it may not be clear to all interested readers what "multi-scale", "processing pipeline", "run process". Find alternative/easier wording or explain (as these terms are necessary and useful later in the manuscript). Define I/O (and consistently all abbreviations), define ESMF correctly.

Abstract section is modified and simplified by removing most of the domain specific jargons.

Introduction

4) p1 I23 Use consistent spelling for Earth System Model (capitalized), introduce abbreviation already here. Also use consistent spelling of Earth (name of our planet) versus earth.

The text is modified based on your suggestions.

5) p2 I4 Unsubstantiated claims "more demanding compared to conventional standalone models, and in many cases, to global climate models". Also standalone models can be computationally demanding and though less complex may employ a higher resolution in uncoupled contexts and lower resolution in coupled context, arriving at the same computational demand. And if global ESM were less demanding, also their resolution would increase aligned to available compute re- sources and user requirements.

The sentence is removed.

6) p2 I4 You have not yet defined "obvious needs". What are "truthful predictions" in a model context? Aren't they rather "accurate hindcasts" and "realistic projections".

The sentence is modified based on your suggestions and moved to the end of the paragraph.

7) p2 I10f avoid "in order", just use "to". Avoid "moreover" (throughout manuscript). Try to condense sentences and leave out all unnecessary words throughout the manuscript.

The sentence is modified based on your suggestions.

8) p2 l12 “are also simplified” is not necessarily true. This “can” be simplified or is sometimes even “enforced”, such as the grid specification in ESMF, or the standard names by CF conventions.

The sentence is modified based on your suggestions.

9) p2 l16ff ESMF suggests to use Theurich 2016 et al. for referencing ESMF. “in addition” does not align with “can be given as examples”. MCT only provides part of the functionality that is present in ESMF (also FMS), as does OASIS (in its different); OASIS may or may not contain MCT, depending on version. There are also more recent developments, such as Jcup3, OMUSE, MOSSCO, MESSy, FABM, CSDMS which you may mention. Please clean up the list, discriminate couplers from coupling frameworks, sort by relationship and highlight key differences or commonalities. A review of older technologies is provided by Bert Jagers 2010.

The more recent reference of ESMF is added to the list. The literature of couplers and coupling frameworks are also extended. Please refer to the supplementary document that includes track-changes.

10) p2 l19 “The ESMs make use of state-of-art modeling frameworks, model components and libraries to have better representation of the earth system processes”. This sentence is irrelevant. “The key component of coupled modeling systems is often the driver”. Please refer to Alexander/Easterbrook (2015) for typical coupling constellations in ESMs. There, it is quite obvious that many models do not employ a driver. You could also use the term “hub-and-spoke” architecture (consistent with your Figure 1) where the driver is the hub. The word “driver” itself is jargon and should be introduced beforehand.

The paragraph is also modified to refer Alexander/Easterbrook (2015) paper that briefly demonstrate the diversity of the current global earth system models.

11) p2 l19 “such as six hourly or daily averages”. This is true only for coupled physical systems. For geology ESMs, typical timescales may be longer (years, centuries), see e.g., CSDMS.

It is removed from the sentence.

12) p2 l23 “Coupling between individual earth system components adds extra overhead... network bandwidth usage, computation, disk I/O and data storage”. Again, not necessarily. Please substantiate or give an example or reference where this applies. In my opinion the real overhead is in the loss of flexibility/modularity: it is preferable to have 1 hub speak a common language to 4 components than have each of the 4 components speak to each of the other three. Though the latter may be less complex, it hinders extensibility of a coupled system.

The misleading sentence is removed from manuscript.

13) p3 l3f Fix articles. As everywhere.

I am aware that there are numerous missing articles in the manuscript and these are fixed in the revised version of manuscript.

14) p3 l7 Don’t overly use “in short”, also throughout manuscript.

It is modified as “as a result” in here.

15) p3 l7 Don’t use judging language such as “brilliant”. This entire sentence could be deleted (and the keyword “exascale” mentioned before.

It is changed to “state-of-art” and “exascale” is deleted.

16) p4 l4ff This paragraph is not needed.

It is removed.

Design

17) p4 l9 “couple four different model components”. I don’t understand. Version 1.0 coupled four components, version 1.1 adds a co-processing component, totalling five. This is also confusing in Figure 1. Modular frameworks such as NUOPC/ESMF do not discriminate scientific models, data components, out-put/visualization per se. All are just “components”. I would suggest to use the term “component” for all five (four of them science models).

The paragraph is modified based on your suggestions.

18) p4 l11 delete “state-of-art”

It is removed.

19) p4 l11 You have not yet introduced “the coupling interfaces” (this may be an article problem). So far, a driver and four models have been introduced. The necessity to add also coupling interfaces, and possibly NUOPC caps (CMI in the framework of Peckham 2013), has not yet been mentioned.

The coupling interface is introduced before its use and hub-and-spoke architecture is also mentioned in here.

20) p4 l16ff delete this paragraph

It is removed.

21) p4 l section heads add ATM (later OCN, WAV, COP) to section heads

They are added

22) p4 l22 For in-text enumerations, please use (1) with double parentheses, and do not write the number in bold face.

It is fixed. Same convention is also used in everywhere in the manuscript.

23) p4 l26 “it is well tested with verified in”. This does not make sense grammatically, please fix. Also, you have a verified model system for South and Eastern European/West Asian regions, but not for the Gulf of Mexico, which you provide as an example for the visualization.

It is fixed. The RegCM atmospheric model component is used because WRF is not ready to couple with co-processing component. I still need to add three-dimensional fields such as mixing ratio etc. along with support of vertical interpolation. We are currently working on it as a part of ongoing national science project and will be ready soon (in version 1.2).

24) p4 l27f Avoid “Additionally, ”. What relevance has “does not support online nesting yet” for the application discussed here. Is online nesting needed for coupling to the co-processing model. Or is it just not “operational” in a sense that RegESM/WRF has not been scientifically proved?

It is fixed. No, there is no need to use on-line nesting to couple with co-processing. It is also not supported in the current version of the coupled modeling system. So, it is removed. We are planning to redesign whole modeling system from scratch to support online nesting among model components but this is our long-term goal for RegESM 2.0. We are also having fully coupled WRF-MITgcm model for Black Sea but the results are not published yet. Along with a help of newly introduced co-processing

component, the Black Sea model will be used to investigate lake-snow effect as a part of same ongoing national project.

25) p5 sections 2.1.1/2.1.2 Align in model descriptions of RegCM and WRF the content. Use the same structure: dynamical core, spatial representation, explicitly modeled states and subgrid-scale parameterizations, sub-modules. This parallel construction helps to compare the ATM science models.

Both sections are restructured to align their content as much as possible. In this case, they have very brief information about models and reader must refer to their own documents to get more information.

26) p5 l9 “the driver and coupling interface are developed by ITU”. The driver should be independent of RegCM, why is this mentioned? What is the coupling interface? Is it the CMI/NUOPC cap? You may choose to introduce those two terms to make clear what you mean by coupling interface. Please describe the cap (e.g. what state variables does it export/import, which transformations does it encompass). You may also elaborate on the changes internal to RegCM (and WRF/MITgcm, WAM/HD)

The sentence that refers to ITU and ENEA is removed. The processes handled by NUOPC cap are listed in here because they are same for both atmospheric model component. The NUOPC cap and details about the implementation are added.

27) p5 l21 “model is modified to exchange data”. Discriminate work done on cap (CMI) and within model (BMI, Peckham 2013).

The text is modified and now the distinction between modifications done in model side and cap is more apparent. In each model section, only work done in model side is described.

28) p5 l23ff All that was said in the ATM section also applies here (parallel structure, elaboration ...)

Both sections are restructured to align their content as much as possible.

29) p6 l2ff Avoid judging language like “fortunately”. Avoid “in general” if possible. “In some studies”, please reference those studies or give a motivation for both cases.

“fortunately” is removed from the manuscript. “In general” is also removed and i referred to our previous work for the bulk flux algorithm.

Turuncoglu, U. U., Giuliani, G., Elguindi, N., and Giorgi, F.: Modelling the Caspian Sea and its catchment area using a coupled regional atmosphere-ocean model (RegCM4-ROMS): model design and preliminary results, *Geosci. Model Dev.*, 6, 283-299, <https://doi.org/10.5194/gmd-6-283-2013>, 2013.

In this study, we have to use bulk flux algorithm because ice model coupled with ROMS (not latest CICE version of ROMS, Budgetell, 2005 version is used) was not working with the direct fluxes provided by atmospheric model.

30) p6 l7f “In the current design of the coupled modeling system, the driver allows to select the desired exchange fields from the predefined list”. Please explain how this works. Is the list like a database with all known fields from all possible coupled models and there is an automated selection of suitable fields?

It is just a list of fields that component could import and export. The automatization could be implemented in future version of the modeling system by using ontologies, common vocabularies and conventions.

31) p6 l15 Leave out example technical detail “REGCM_COUPLING”. I would appreciate a list of changes in the supplementary material, if that is practical to do.

It is removed. The documentation of the RegESM modeling system includes all those tiny details. The reader could refer to the following link <https://github.com/uturuncoglu/RegESM>

32) p6 l23 define PROTEUS abbreviation

Actually, I searched in web and their publications but i could not find the source of the abbreviation but ENEA is using it for their publications and web site. So, I prefer to keep it as it is.

33) p6 l26 PBL has already been defined

It is corrected.

34) p6 l26f third-generation wave model. What is “pure” physics? Use an en-dash to indicate a relationship in wave-wave / wave–wave (the second one is correct typography)

“pure physcis” is removed. wave-wave is also written with en-dash now.

35) p6/7 l32 WAM is not by ENEA but by GKSS (now HZG) in Germany, I believe. Please attribute correctly. Describe changes to original model (here in text or as table in SOM).

It is fixed now. The list of changes in WAV side is also included.

36) p7l5 Unit of z0(m).

It is added.

37) p7 l20f Explain your motivation for the two different ways. Do they pertain to ROMS and MITgcm coupling, respectively? How are they chosen?

The first option is used to define river plumes correctly while the second one is generally used to distribute river discharge to a large areal extent over the ocean. These are defined in the configuration file of the driver. The section is also modified to include this information.

38) p7 l22f The change to output format is irrelevant in this context.

It is removed.

39) p7 l30f “The ESMF is chosen because ... of the NUOPC”. Please explain the relationship between ESMF and NUOPC. Why do you chose NUOPC in addition to ESMF, this needs elaboration for readers who are not familiar with NUOPC.

The section is extended to include more information about relationship between ESMF and NUOPC interface.

40) p8 l2f “It also provides the capability of transferring computational grids”; here, “it” should refer to ESMF, not NUOPC.

It is fixed.

41) p8 l2f “NUOPC layer to support various configuration of component interactions such as defining multiple coupling time steps (fast and slow time steps; Fig. 2)”. There are other frameworks that provide add this capability to ESMF, namely MAPL and MOSSCO, please reference and contrast.

Actually, this feature is mainly inherited from ESMF by MAPL and MOSSCO. I think it is better to reference to ESMF/NUOPC for it.

42) p8 l9f “connector components provided by NUOPC layer. Connector components are mainly used to create link between individual model components and driver”. As far as I know, RegESM includes its

own instance of a NUOPC connector, which is a single one for all connections between the components. Please elaborate on the design and functionality of the connector.

There is no single connector in the modeling system. For example, when RegESM is configured to couple only atmosphere and ocean components. The modelling system creates two connectors to represent ATM-OCN and OCN-ATM interactions. This is little bit different when atmosphere model coupled with co-processing component. In this case, there is only one connector because only ATM-COP interaction is valid. COP component does not send any information to other components (like a sink). The section is extended to include this information.

43) p8 l18f You name stability as an advantage of semi-implicit coupling. Also add draw-backs of semi-implicit and advantages of implicit time stepping.

The paragraph is extended to include more information about different coupling schemes.

44) p8 l20f delete “mainly” and “In this case”

They are removed.

45) p8 l28 You may want to add the term “load balancing” for describing the challenges in concurrent coupling. There should be plenty of literature that describes load- balancing and possible ways to minimise this. In the geosciences, usually all OASIS-coupled models face this challenge.

Yes, the right term is load-balancing. A reference is added about LUCIA (Load-balancing Utility and Coupling Implementation Appraisal) tool for load-balancing analysis in OASIS-MCT based coupled systems.

46) p8 l31f The description of regridding could be a subsection, section 2.6 “Connector”. How do other coupled model systems handle this (any references available?). Recently, I implemented into MOSSCO a very similar scheme using bilinear for interpolation and nearest neighbour for extrapolation, so I believe this is a very good way to handle this (but it is not published yet). Possibly, describe how ESMF 8 handles this rather than pointing vaguely to ongoing development.

I prefer to keep it as it is. The special interpolation implemented in RegESM modeling system is a part of driver.

47) p9 l14 Align your description with the terms used in Figure 4 (see comments below on this figure).

We used field names (Field_A, Field_B and Field_C) in also manuscript. The paragraph is also extended to describe the algorithm clearly.

Integration of co-processing

48) p9 l25 Use an em-dash “—” instead of a hyphen. One sentence is not a paragraph, so join with next paragraph.

It is fixed.

49) p9 l28 Define “conventional” or give a reference to such approaches. Define pipeline in this context.

The conventional co-processing enabled simulation systems interacts with single physical model component such as atmosphere along with co-processing support. This is defined also in text and references are added.

... A visualization pipeline integrates a data flow network in which computation is described as a collection of executable modules that are connected in a directed graph representing how data moves between modules (Moreland, 2013). There are three types of modules: sources (file readers and

synthetic data generators), filters (transforms data), and sinks (file writers and rendering module that provide images to a user interface) in the visualization pipeline. ...

50) p9 I30 How is “wrapper layer” different from Component Model Interface (CMI) or NUOPC cap or ESMF component interface?

A NUOPC cap is defined for co-processing component along with adaptor code. In this case, adaptor code is an interface for ParaView, Catalyst API and NUOPC cap passes information from ESMF to adaptor code. The text slightly modified to clear the design.

51) p10 I3 On what “other hand”? Describe the relationship between the adaptor and its NUOPC cap

It is removed. It is defined in previous paragraph.

Benchmark

52) p14 I26 The “driver component introduces additional 5-10%”. In ESMF documentations, usually below 5% overhead is assumed. this makes sense as you to the SMM twice for each interpolation of mask extrapolation. It would be interesting to see whether the generic implementation of extrapolation is more efficient in ESMF 8 (out of scope of this MS).

I agree. As far as i know, the ESMF developers was trying to find a way to combine weight matrix of multiple interpolation (including extrapolation) into a single one. Similar methodology is using in transformation (scale, rotation, translation etc.) matrixes using homogeneous coordinates but i am not sure it could be used in regridding or not.

53) p14 I35 “ includes vertical interpolation to map data from sigma coordinates to height coordinates”. Why is this interpolation step necessary? In principle, the visualization should equally work on sigma layers. And is the interpolation performed within the ESMF connector, or within a Paraview pipeline?

I did not try yet but yes the visualization works with sigma coordinates without any problem. The vertical interpolation is introduced to have a consistency in the data coming from atmosphere and ocean. By this way, the vertical scales of the data can be compared without any problem. In general, both atmosphere and ocean components use sigma coordinates with different definitions. The interpolation is done in ESMF cap not in ParaView side. It could be done in ParaView side also but in this case all grid related parameters such as stretching functions etc. need to be passed to ParaView, Catalyst and special ProgrammableFilter need to be developed.

54) p15 I2 the computational demand for visualization “require 10-40% extra” is rather high and its evaluation would probably change depending on whether it is more 10% (acceptable) or 40% (not acceptable). The benchmark using software rendering with Mesa is not ideal to demonstrate this, especially as many new HPC systems come with dedicated GPU nodes that could much reduce the visualization overhead.

It is clear that Mesa is not right way to measure the performance of the co-processing component. The overall performance of the used computing system dominates the results in our case but we don't have accesses to a system with GPU accelerators. In the early stage of the performance benchmark, Dell provided us a grant in newly installed University Manchester system (10000 core/hour) but the system is mainly designed for GPU intensive and AI type researches and the nodes have small number of core (10 cores) but four NVIDIA P100 GPU. In fact, our test simulations are CPU intensive and requires high amount of compute resource (or cores) for the high-resolution simulations and rendering only done on a single GPU (limitation of ParaView, Catalyst and used filters). As a result, couple of benchmark run spend all allocated resources (unused GPU resources was also accounted) and the system was not used for the benchmark. There was also issue related with buggy NVIDIA driver and ParaView protobuf library. In the future, along with the development of m-VTK (GPU accelerated filters) it could be possible to use multi-GPU systems.

Results and Conclusions

55) p15 l31 This section is not well named. I suggest "Demonstration application" but make sure to choose something more elaborate than "results"

It is changed as suggested.

56) p15 l35 oblivious => obvious

It is fixed.

57) p16 l3 Explain how you choose between live mode and co-processing modes. Are these two different models? Or is this done by way of a configuration file. Or, is it possible to attach live viewing to any running system that has co-processing enabled?

No, it is not a different model or configuration. The selection of the mode is controlled by the Python script generated using ParaView, co-processing plugin. The user could also activate live visualization mode, just by changing a single line of code (coprocessor.EnableLiveVisualization needs to be set as True) in the co-processing Python script. Yes, if live visualization is enabled, the user can attach to the simulation anytime and pause it to analyze the results. This information is added to section.

Figures

58) Figure 1 Very clear and readable, consistent color and design with NUOPC web page. Please see my suggestions to treat everything as component, regardless of science "MODEL" or visualization "COMP". It is not clear from the text what "redist" is; also, this feature is not used when running sequentially. I also do not understand the many "regrid" arrows, as regridding occurs when the driver transports a field from one to another component, not from the component to the driver. This is confusing.

The figure is modified. All the boxes are named as "COMPONENT" and the texts are also removed from the arrows.

59) Figure 4 Rather unreadable. Please redesign. (1) Avoid bridges (this is possible by routing the arrow "Create ESMF FIELD_B" north to "Create ESMF FIELD_C". (2) don't use same line thickness/color for outlining the boxes around src/dst grid, rather make them visually less intrusive to highlight the flowchart. (3) Abstract away 1.0, LARGEST, "over sea" or other value-based masking, if possible.

The figure is modified. The hop is solved by changing the position of the arrow. The dashed line is used in the boxes and color is changed to grey to move focus to workflow. It is hard to abstract used values and mask values. The algorithm is tested with this configuration and it is better to keep them as it is to have a reproducible result (at least for finding mapped and unmapped grid points). I am also using same methodology using NCL ESMF interface to create forcing for ocean models and it works better than standard extrapolation method (based on solution of Poisson Eq.) provided by NCL itself.

60) Figure 7 It is confusing that the visualization 2x2 tiles don't geographically overlap for data from OCN and ATM in CPL. This is not needed, but confusing at first. Maybe give a hint to the reader that this is not a problem.

The order of plots and labels of Fig 6 and Fig 7 was wrong. It is fixed now. Following section is also included to the manuscript

... In this case, ATM and OCN model components do not need to geographically overlap for co-processing. The only limitation is that the ATM component must cover the entire OCN model domain for an ATM-OCN coupled system because the ATM component provides the surface boundary condition for OCN component. ...

61) Figures 9/10 It is very difficult to compare ATM versus OCN performance using different y scales. I recommend to use the same ylog-scale for all panels in figs 9 and 10. Also try loglog. Tile sizes are hard to read, please move text from lines. Calculate all speedup relative to 140 cores, so that you don't have different reference points. Explain model versions like RegCM_r6274, delete UHeM. Avoid overlapping graphics and text.

The speed-up calculation of coupled model simulations starts from 140 core because this is the minimum number of cores that allows to run the modeling system. For standalone simulations, it is possible to run the model with 28 cores (single node). As a result, it was used 28 cores for standalone and 140 cores for coupled model simulations to calculate the speedup. The plots are modified to have consistent x and y axis (log scale) as well as number of cores used in the speed-up calculation (140 cores) except plot for standalone ocean model. In this case, using same log scale for it does not give good results as expected for example the effect of tile configuration cannot be seen clearly because the benchmark results fall into a very narrow interval. To that end, i prefer to keep results of standalone ocean simulations as it is. I also increased font sizes and move the text little bit far from the markers for standalone ocean model plot. The texts that indicate model version and name of the computing system that is used in the benchmark are removed because they are already mentioned in the manuscript.

62) Figure 10 8 lines in a graph is too messy. Even if on ylog, this may be difficult. Possibly choose different or more subpanels (e.g. CPL_LR + CPL_HR in one panel, then P1, P2, P3 each in one panel). Or use more colors for lines or different line styles ...

The plot is modified. Now it has four panel. The first one (a) compares coupled model simulations (w/o co-processing component), and the rest compares coupled model simulations with co-processing component enabled (LR vs. HR). (b) for P1 visualization pipelines, (c) for P2 visualization pipelines and (d) for P3 visualization pipelines. The both y scales (the left one uses log scale) are also consistent now.

63) Figure 11 Zoom in to Paraview Window only (delete lower and upper OS information bands)

It is fixed.

64) Figure 13 Use kg kg⁻¹ and the like, not the slash for division in units.

The figure label is fixed.

Code

65) I have been able to download and compile all components, except for getting the catalyst to run. It would be helpful to provide a fully functional reference system as a docker container, for example.

The Docker container was used to do online demo of the modeling system in the last NVIDIA GTC (GPU Technology Conference). More information about demo case and created Docker container (using software rendering) can be found in following public repository (DOI is also created by Zenodo and referenced in code availability section).

https://github.com/uturuncoglu/GTC2018_demo

There is also Docker container (NVIDIA docker need to be installed - <https://github.com/NVIDIA/nvidia-docker>) that supports NVIDIA GPUs and can be found in following link

<https://drive.google.com/file/d/1hz0Frbawm2UxNtSBnjlrGSHlqDk1kZFY/view?usp=sharing>

In this case, the file size is greater than upper limit of GitHub LFS (Large File Support; 2 GB) and it is shared with Google Drive. After getting file following commands can be used to run the Docker container and low-resolution version of coupled model with co-processing support.

- 1) import container
docker import nvidia_opengl_gtc2018-egl.tar.gz
- 2) list images to retrieve IMAGE ID
docker images
- 3) tag IMAGE (52ebbd92125 is just an example for Image ID, use your own from previous command)
docker tag 52ebbd92125 nvidia/opengl:gtc2018-egl
- 4) run container and get interactive shell
nvidia-docker run -it nvidia/opengl:gtc2018-egl /bin/bash
- 5) go to simulation directory (all required libraries installed under /opt/progs)
cd /opt/progs/COP_LR
- 6) run simulation (it will produce png files for each coupling time step)
./run.sh

A new section (Sec. 6) is also included to the manuscript to discuss interoperability, portability and reproducibility.

Supplementary videos

66) Useful and nice! Please make sure the video dois are referenced in the text, and add to the videos a link to your publication.

The video DOIs are included into the manuscript and the reference sections.

Towards in-situ visualization integrated ~~earth-system-models~~ Earth System Models: RegESM 1.1 regional ~~modelling-modeling~~ system

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Abstract. The data volume ~~being~~ produced by regional and global multi-component ~~earth-system-models~~ Earth System Models are rapidly increasing ~~due to because of~~ the improved spatial and temporal resolution of the model components, ~~the~~ sophistication of the used numerical models ~~in terms of regarding~~ represented physical processes and their ~~non-linear complex complex non-linear~~ interactions. In particular, very ~~short time steps have small time step needs~~ to be defined in ~~multi-component and multi-scale~~ non-hydrostatic ~~modelling systems~~ high-resolution modeling applications to represent the evolution of the fast-moving processes such as turbulence, extra-tropical cyclones, convective lines, jet streams, internal waves, vertical turbulent mixing and surface gravity waves. Consequently, the ~~used-employed~~ small time steps cause extra computation and disk ~~I/O~~ input-output overhead in the ~~used-modelling-modeling~~ system even if today's most powerful high-performance computing and data storage systems are ~~being~~ considered. Analysis of the high volume of data from multiple ~~earth-system-model~~ Earth System Model components at different temporal and spatial resolution also poses a challenging problem to efficiently perform integrated data analysis of the massive amounts of data by relying on the conventional post-processing methods available today. This study ~~basically-mainly~~ aims to explore the feasibility and added value of integrating existing in-situ visualization and data analysis methods with the model coupling framework (~~ESMF~~) to increase interoperability between multi-component simulation code and data processing ~~pipelines-systems~~ by providing easy to use, efficient, generic and standardized modeling environment for ~~earth-Earth~~ system science applications. The new data analysis approach enables simultaneous analysis of the vast amount of data produced by multi-component regional ~~earth-system-models (atmosphere, ocean etc.) during the run process. The methodology~~ Earth System Models during the runtime. The presented methodology also aims to create an integrated modeling environment for analyzing fast-moving processes and their evolution in both time and space to support a better understanding of the underplaying physical mechanisms. The state-of-art approach can also be ~~used-employed~~ to solve common problems in ~~earth-system-model development workflow such as the model development cycle;~~ designing new sub-grid scale parametrizations (~~convection, air-sea interaction etc.~~) that requires inspecting the integrated model behavior in a higher temporal and spatial scale ~~during the run or simultaneously and~~ supporting visual debugging of the multi-component modeling systems, which usually are not facilitated by existing model coupling libraries and modeling systems.

1 Introduction

The multi-scale and inherently coupled ~~(atmosphere, ocean, land etc.) earth system models~~ Earth System Models (ESMs) make them challenging to study and understand. Rapid developments in ~~earth~~ Earth system science, as well as in ~~high-performance~~ high-performance computing and data storage ~~systems~~, have enabled fully coupled regional or global ~~Earth System Models~~ (ESMs) ~~ESMs~~ to better represent relevant processes ~~and~~, complex climate feedbacks, and interactions among ~~the~~ coupled components. ~~Regional ESMs are generally used~~ In this context, regional ESMs are employed when the spatial and temporal resolution of the global climate models are not sufficient to resolve local features such as complex topography, land-sea gradients and the influence of human activities in a smaller spatial scale. ~~The complexity of the fully coupled state-of-art regional ESMs have made them computationally more demanding compared to conventional standalone models, and in many cases, to global climate models. To that end, there are obvious needs to develop novel modelling tools, model coupling frameworks (at the required level of sophistication in terms of both physics and computational methods) as well as innovative and efficient modelling systems to enable truthful predictions based on accurate and realistic representation of earth systems~~ Along with the development of the modeling systems, specialized software libraries for the model coupling become more and more critical to reduce the complexity of the coupled model development and increase the interoperability, reusability, and efficiency of the existing modeling systems. Currently, the existing model coupling software libraries have two main categories: couplers and coupling frameworks.

Couplers are mainly specialized in performing specific operations more efficiently and quickly such as coordination of components and interpolation among model components. For example, OASIS3 (Valcke, 2013) uses multiple executable approaches for coupling model components but sequentially performing internal algorithms such as sparse matrix multiplication (SMM) operation for interpolation among model grids become a bottleneck along with increased spatial resolution of the model components. To overcome the problem, OASIS4 uses parallelism in its internal algorithms (Redler et al., 2010), but OASIS3 coupler interfaced with the Model Coupling Toolkit (MCT; Jacob et al., 2005; Larson et al., 2005) to develop OASIS3-MCT that provides a parallel implementation of interpolation and data exchange. Besides generic couplers like OASIS, domain-specific couplers such as Oceanographic Multi-purpose Software Environment (OMUSE; Pelulessy et al., 2017) that aims to provide a homogeneous environment for ocean modeling to make verification of simulation models with different codes and numerical methods and Community Surface Dynamics Modeling System (CSDMS; Overeem et al., 2013) to develop integrated software modules for modeling of Earth surface processes are introduced.

A ~~modeling framework is defined~~ coupling framework is as an environment for coupling model components through a ~~common calling interface~~. The modeling framework ~~standardized calling interface and~~ aims to reduce ~~the~~ complexity of regular tasks such as performing spatial interpolation across different computational grids and ~~to transfer~~ transferring data among model components ~~, in order to increase the efficiency and interoperability of multi-component coupled model systems by providing standardized calling interfaces. Moreover~~ modeling systems. Besides, the synchronization of the execution of individual model components ~~and~~, a coupling framework can simplify the exchange of metadata ~~among them are also simplified with model coupling frameworks~~ related to model components and exchanged fields through the use of existing

conventions such as CF (Climate and Forecast) convention. The Earth System Modeling Framework (ESMF) is one of the most ~~popular example for this approach (???)~~famous examples of this approach (Theurich et al., 2016). The ESMF consists of a standardized superstructure for coupling components of Earth system applications through a robust infrastructure of high-performance utilities and data structures that ensure consistent component behavior ~~(Hill et al., 2004).~~
5 ~~In addition to the ESMF model coupling framework, the Model Coupling Toolkit (MCT; Jacob et al., 2005; Larson et al., 2005), Model Coupling Environmental Library (MCEL; ?), OASIS (Redler et al., 2010; Valeke, 2013) and C-Coupler (?) can be given as other examples of this approach.~~

~~The ESMs make use of state-of-art modeling frameworks, model components and libraries to have better representation of the earth system processes. (Hill et al., 2004).~~ The ESMF framework is also extended to include the National Unified Operational Prediction Capability (NUOPC) layer. The NUOPC layer simplifies component synchronization and run sequence by providing additional programming interface between coupled model and ESMF framework through the use of NUOPC “cap”. In this case, a NUOPC “cap” is a Fortran module that serves as the interface to a model when it is used in a NUOPC-based coupled system. ~~The key component of coupled modeling systems is often the driver, which is mainly responsible for term~~
10 “cap” is used because it is a small software layer that sits on top of a model code, making calls into it and exposing model data structures in a standard way. In addition to generic modeling framework like ESMF, Modular System for Shelves and Coasts (MOSSCO; Lemmen et al., 2018) creates a state-of-art domain and process coupling system by taking advantage of both ESMF and Framework for Aquatic Biogeochemical Models (FABM; Bruggeman and Bolding, 2014) for marine coastal Earth system community.

The recent study of Alexander and Easterbrook (2015) to investigate the degree of modularity and design of the existing global climate models reveals that the majority of the models use central couplers to support data exchange, spatial interpolation~~and synchronization between model components, subject to their individual computational grids, and synchronization among model components.~~ In this approach, direct interaction ~~do does~~ not have to occur between individual model components or modules, since the ~~data transfer is managed by the specialized driver component . Coupling between individual earth system components adds extra overhead and complexity to the overall modeling system in terms of network bandwidth usage, computation, disk I/O and data storage.~~
25 ~~Due to the high volume of data produced by multiple model components, the results are generally stored in a limited temporal resolution such as six hourly or daily averages, which are processed after numerical simulations are finished. This conventional approach is commonly known as post-processing. A typical configuration, e.g. a thirty years simulation of a fully coupled regional atmosphere-ocean model might produce some Terabyte of output (in four dimensions; time, height or depth, latitude and longitude), which strongly depend on horizontal and vertical resolution of model components, the number of variables and the time interval defined to store the simulation results. In this case, the post-processing step commonly involves creating temporal (i.e. seasonal climatology, daily and /or monthly averages) and spatial averages, time series, cross-sections in a defined axis and/or custom pathways, added value information produced by set of statistical methods and the visualization of the model results.~~
30 specific coupler component manages the data transfer. This approach is also known as the hub-and-spoke method of building a multi-component coupled model. A key benefit of using a hub-and-spoke approach is that it creates a more flexible and efficient environment for designing sophisticated multi-component
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modeling system regarding represented physical processes and their interactions. The development of the more complex and high-resolution modeling systems leads to an increased demand for both computational and data storage resources. In general, the high volume of data produced by the numerical modeling systems may not ~~enable to store~~ allow storing all the critical and valuable information to use later, despite recent advances in ~~disk storage~~ systems. As a result, the simulation results
5 are stored in a limited temporal resolution (i.e., monthly averages), which are processed after numerical simulations finished (post-processing). The poor representation of the results of numerical model simulations prevents to analyze the fast-moving processes such as extreme precipitation events, convection, turbulence and non-linear interactions among the model components ~~cannot be analyzed in~~ in a high temporal and spatial ~~scales~~ scale with the conventional post-processing approach.

The analysis of leading high-performance computing systems reveals that the rate of disk input-output (I/O) performance
10 is not growing at the same speed as the peak computational power of the systems (Ahern, 2012; Ahrens, 2015). The recent report of U.S. Department of Energy (DOE) also indicates that the expected rate of increase in I/O bandwidth (100 times) will be slower than the peak system performance (500 times) of the new generations of exascale computers (Ashby et al., 2010). ~~In addition~~ Besides, the movement of large volumes of data across relatively slow network bandwidth servers ~~fail~~ fails to match the ultimate demands of data processing and ~~archiving to archive~~ tasks of the present ~~high-resolution~~ high-resolution
15 ~~multi-component earth system models. In short~~ ESMs. As a result, the conventional post-processing approach has become a bottleneck in monitoring and analysis of fast-moving processes that require very high spatial resolution, due to the present technological limitations in high-performance computing and storage systems (Ahrens et al., 2014). In the upcoming ~~exascale~~ computing era, ~~brilliant~~ state-of-art new data analysis and visualization methods are needed to ~~evocatively~~ overcome the above limitations evocatively.

Besides ~~to~~ the conventional data analysis approach, the so-called in-situ visualization and co-processing approaches allow
20 researchers to ~~simultaneously~~ analyze the output while running the numerical simulations simultaneously. The coupling of computation and data analysis helps to facilitate efficient and optimized data analysis and visualization pipelines and boosts the data analysis workflow. Recently, a number of in-situ visualization systems for analyzing numerical simulations of ~~earth~~ Earth system processes have been implemented. For instance, the ocean component of Model for Prediction Across Scales
25 (MPAS) has been integrated with an image-based in-situ visualization tool to examine the ~~important~~ critical elements of the simulations and reduce the data needed to preserve those elements by creating a flexible work environment for data analysis and visualization (Ahrens et al., 2014; O’Leary et al., 2016). Additionally, the same modeling system (MPAS-Ocean) has been used to study eddies in ~~large-scale~~ large-scale, high-resolution simulations. In this case, the in-situ visualization workflow is designed to perform eddy analysis at higher spatial and temporal resolutions than available with conventional post-processing facing
30 storage size and I/O bandwidth constraints (Woodring et al., 2016). Moreover, a regional weather forecast model (Weather Research and Forecasting Model; WRF) has been integrated with in-situ visualization tool to track cyclones based on an adaptive algorithm ~~to perform efficient online visualization (Malakar et al., 2012).~~ In spite of (Malakar et al., 2012). Despite the lack of generic and standardized implementation for integrating model components with in-situ visualization tools, the previous studies have shown that in-situ visualization ~~is able to~~ can produce analyses of simulation results, revealing many details in an
35 efficient and optimized way. It is ~~obvious~~ evident that more generic implementations could facilitate ~~easy~~ smooth integration of

the existing standalone and coupled ~~earth system models~~ ESMs with available in-situ visualization tools (Ahrens et al., 2005; Ayachit, 2015; Childs et al., 2012) and improve interoperability between such tools and non-standardized numerical simulation codes.

The main aim of this paper is to explore the added value of integrating in-situ analysis and visualization methods with a model coupling framework (ESMF) to provide in-situ visualization for easy to use, generic, standardized and robust scientific applications of ~~earth~~ Earth system modeling. The implementation allows existing ~~earth system models~~ ESMs coupled with the ESMF library to take advantage of in-situ visualization capabilities without extensive code restructuring and development. Moreover, the integrated model coupling environment allows sophisticated analysis and visualization pipelines by combining information coming from multiple ~~earth system model~~ ESM components (i.e., atmosphere, ocean, wave, land-surface) in various spatial and temporal resolutions. Detailed studies of ~~key~~ fundamental physical processes and interactions among model components are vital to the understanding of complex physical processes and could potentially open up new possibilities for the development of ~~earth system models~~ ESMs.

~~The next section (Sect. 2) describes the design of a fully coupled regional earth system model used in this study. Section 3 provides information about the implementation and design of the in-situ visualization integrated modelling framework employed. Then, the initial results from newly designed modeling framework will be demonstrated in Section 4, along with some benchmark results (Sect. 5). Finally, a summary and discussion are given in the last section (Sect. 6).~~

2 The Design of the Modeling System

The RegESM (Regional Earth System Model; 1.1) modeling system ~~is able to couple four~~ can use five different model components ~~(atmosphere, ocean, wave and river routing)~~ to support many different modeling applications that might require detailed representation of the interactions among different ~~earth~~ Earth system processes (Fig. 1a-b). The ~~state-of-art~~ implementation of the modeling system follows the hub-and-spoke architecture. The driver that is responsible for the orchestration of the overall modeling system resides in the middle and acts as a translator among model components ~~. In the design of the coupled modeling system, the coupling interfaces and driver are mainly developed by Istanbul Technical University (ITU) while MITgem oceanmodel component is modified by the Italian National Agency for New Technologies, Energy and Sustainable Economic Development (ENEA) to work as a part of RegESM modeling system (Turuncoglu and Sannino, 2017).~~

~~The following sections basically aim to give brief information about the individual model components, which are used to construct the modeling system, as well as the design details of the driver to combine independently developed and maintained model components in an efficient and standardized way (atmosphere, ocean, wave, river routing, and co-processing). In this case, each model component introduces its NUOPC cap to plug into the modeling system. The modeling system is validated in different model domains such as Caspian Sea (Turuncoglu et al., 2013), Mediterranean Basin (Surenkok and Turuncoglu, 2015; Turuncoglu, and Black Sea Basin.~~

2.1 Atmosphere Models (ATM)

The flexible design of RegESM modeling system allows ~~to choose~~ choosing a different atmospheric model component (ATM) in the configuration of the coupled model for a various type of application. Currently, two different atmospheric model ~~are is~~ compatible with RegESM modeling system: ~~➤(1)~~ ➤(1) RegCM4 (Giorgi et al., 2012), which is developed by the Abdus Salam International Centre for Theoretical Physics (ICTP) and ~~➤(2)~~ ➤(2) the Advanced Research Weather Research and Forecasting (WRF) Model (ARW; Skamarock et al., 2005), which is developed and sourced from National Center for Atmospheric Research (NCAR). ~~The details of the individual atmospheric model can be found in following section but RegCM4~~ In this study, RegCM 4.6 is selected as an atmospheric model component ~~in this study because it is well tested with verified in different model domains such as Caspian Sea (Turuncoglu et al., 2013), Mediterranean Basin (Surenkok and Turuncoglu, 2015; Turuncoglu and Sannino, 2015) and Black Sea. Additionally, because~~ the current implementation of ~~RegESM-WRF-WRF coupling~~ WRF coupling interface is still experimental and does not support ~~online nesting yet but this will be included in~~ coupling with co-processing component yet, but the next version of the modeling system (RegESM ~~2.0~~ 1.2) will be able to couple WRF atmospheric model with co-processing component. The NUOPC cap of atmospheric model components defines state variables (i.e., sea surface temperature, surface wind components), rotates the winds relative to Earth, apply unit conversions and perform vertical interpolation to interact with

15 the newly introduced co-processing component.

2.1.1 RegCM

The dynamical core of the RegCM4 is based on the primitive equation, hydrostatic version of the National Centre for Atmospheric Research (NCAR) and Pennsylvania State University mesoscale model MM5 (Grell, 1995). The ~~model latest version~~ of the model (RegCM 4.6) also supports non-hydrostatic dynamical core to support applications with high spatial resolutions (< 10 km). The model includes two different land surface models: ~~➤(1)~~ ➤(1) Biosphere-Atmosphere Transfer Scheme (BATS; Dickinson et. al., 1989) and ~~➤(2)~~ ➤(2) Community Land Model (CLM), version 4.5 (Tawfik and Steiner, 2011). The model also includes ~~specialized~~ specific physical parameterizations to define air-sea interaction over the sea and lake (one-dimensional lake model; Hostetler et al., 1993). The Zeng Ocean Air-Sea Parameterization (Zeng et al., 1998) is ~~basically~~ extended to introduce the atmosphere model as a component of the coupled modeling system. In this way, the atmospheric model ~~is able to can~~ exchange both two and three-dimensional fields ~~(i.e. sea surface temperature, surface roughness, runoff, surface wind speed, cloud liquid water content)~~ with other model components such as an ocean, wave and river routing components that are active in an area inside of the atmospheric model domain as well as in-situ visualization component. ~~In this design, the driver and coupling interface are developed by ITU to adapt easily to the newer version of RegCM model without major code change in the model component and the driver. In this study, specifically RegCM 4.6 is used to perform in-situ visualization integrated~~

30 ~~simulations.~~

2.1.2 WRF

~~The WRF~~

The WRF model consists of fully compressible non-hydrostatic equations, and the prognostic variables include the three-dimensional wind, perturbation quantities of pressure, potential temperature, geo-potential, surface pressure, turbulent kinetic energy and scalars (i.e., water vapor mixing ratio, cloud water). The model is suitable for a broad range of applications and has a variety of options to choose parameterization schemes for ~~convection,~~ the planetary boundary layer (PBL), ~~convection,~~ explicit moisture, radiation, and soil processes to ~~make available investigation of different earth support analysis of different Earth~~ system processes. The ~~model consists of fully compressible non-hydrostatic equations and the prognostic variables include the three-dimensional wind, perturbation quantities of pressure, potential temperature, geo-potential, surface pressure, turbulent kinetic energy and scalars (water vapor mixing ratio, cloud water etc)~~ PBL scheme of the model has a significant impact on exchanging moisture, momentum, and energy between air and sea (and land) due to the used alternative surface layer options (i.e., drag coefficients) in the model configuration. A few modifications are done in WRF (version 3.8.1) model itself to couple it with RegESM modeling system. These modifications include rearranging of WRF ~~time-related~~ time-related subroutines, which are inherited from the older version of ESMF Time Manager API (Application Programming Interface) that was available in 2009, to compile model with the newer version of ESMF library (version 7.1.0) together with the older version that requires mapping of time manager data types between old and new versions. ~~In addition, the model is modified to exchange data with driver component to support different coupled model applications such as atmosphere-ocean interaction.~~

2.2 Ocean Models (OCN)

The current version of the coupled modeling system supports two different ocean model components (OCN): ~~➤~~ (1) Regional Ocean Modeling System (ROMS revision 809; Shchepetkin and McWilliams, 2005; Haidvogel et al., 2008), which is developed and distributed by Rutgers University and ~~➤~~ (2) MIT General Circulation Model (MITgcm version c63s; Marshall et al., 1997a, b). In this case, ROMS and MITgcm models are selected due to their large user communities and different vertical grid representations. Although the selection of ocean model components ~~depend~~ depends on user experience and application, often the choice of vertical grid system has a determining role in some specific applications. For example, the ROMS ocean model uses terrain following (namely s-coordinates) vertical grid system that allows better representation of the coastal processes but MITgcm uses z levels and generally used for the applications that ~~involves~~ involve open oceans and seas. Similar to the atmospheric model component, both ocean models ~~(ROMS and MITgcm)~~ are slightly modified to allow data exchange with the other model components. In the current version of the coupled modeling system, there is no interaction between wave and ocean model components, which could be crucial for some applications (i.e., surface ocean circulation and wave interaction~~ete~~) that need to consider the two-way interaction between waves and ocean currents. ~~Fortunately, there is a plan to implement ocean-wave interface in the future release of the~~ The exchange fields defined in the coupled modeling system (RegESM 2.0). ~~In general, the exchange fields~~ between ocean and atmosphere ~~closely~~ strictly depend on the application and the studied problem. In some studies, the ocean model requires heat, freshwater and momentum fluxes to be provided by the atmospheric component, while in others, the ocean component retrieves ~~atmospheric data~~ surface atmospheric conditions (i.e., surface temperature, humidity, surface pressure, wind components, precipitation) to calculate fluxes internally, by using bulk formulas (Turuncoglu et al., 2013). In the current design of the coupled modeling system, the driver allows ~~to select~~ selecting

the desired exchange fields from the predefined list of the available fields. The exchange field list is a simple database with all known fields that can be exported or imported by the component. In this way, the coupled modeling system can be adapted to different applications without any code customizations in both the driver and individual model components.

2.2.1 ROMS

- 5 The ROMS is a three-dimensional, free-surface, terrain-following numerical ocean model that solves the Reynolds-averaged Navier-Stokes equations using the hydrostatic and Boussinesq assumptions. The governing equations are in flux form, and the model uses Cartesian horizontal coordinates and sigma vertical coordinates with three different stretching functions. The model also supports second, third and fourth order horizontal and vertical advection schemes for momentum and tracers via its preprocessor flags. ~~To allow coupling with RegESM modeling system, a set of preprocessor flags such as REGCM_COUPLING are included to the model.~~
- 10

2.2.2 MITgcm

- The MIT general circulation model (MITgcm) is a generic and widely used ocean model that solves the Boussinesq form of Navier-Stokes equations for an incompressible fluid. It supports both hydrostatic and non-hydrostatic applications with a spatial finite-volume discretization on a curvilinear computational grid. The model has an implicit free surface in the surface and partial
- 15 step topography formulation to define vertical depth layers. The ~~model~~ MITgcm model supports different advection schemes for momentum and tracers such as centered second order, third-order upwind and second-order flux limiters to support a variety of applications. The model used in the coupled modeling system is slightly modified by ENEA to allow data exchange with other model components. The detailed information about the regional applications of the MITgcm ocean model was initially described in the study of Artale et al. (2010) using ~~PROTEUS modeling system, which is also developed by ENEA~~ PROTHEUS
- 20 modeling system specifically developed for the Mediterranean Sea.

2.3 Wave Model (WAV)

- Surface waves play a crucial role in the dynamics of ~~the planetary boundary layer (PBL)~~ PBL in the atmosphere and the currents in the ocean. ~~To have~~ Therefore, the wave component is included in the coupled modeling system to have a better representation of atmospheric PBL and ~~the~~ surface conditions (i.e., surface roughness, friction velocity, wind speed), ~~the wave component is included to the coupled modeling system.~~
- 25 In this case, the wave component is based on WAM Cycle-4 (4.5.3-MPI). The WAM is a third-generation model ~~, based on pure physics~~ without any assumption on the spectral shape (Monbaliu et al., 2000). It considers all the main processes that control the evolution of a wave field in deep water, namely the generation by wind, the nonlinear ~~wave-wave~~ wave-wave interactions, and also white-capping. ~~To include WAM model (provided by ENEA) as a component of coupled modeling system, the model again~~ The model is initially developed by Helmholtz-Zentrum Geesthacht
- 30 (GKSS, now HZG) in Germany. The original version of the WAM model is slightly modified to ~~exchange fields with other model components. In this case, RegCM4 atmospheric model component provides~~ retrieve surface atmospheric conditions

(i.e., wind speed components or friction velocity and wind direction) ~~to wave model and receives surface roughness from~~ the RegCM4 atmospheric model and send back calculated surface roughness. In the current version of the modeling system, wave component cannot be coupled with the WRF model due to the missing modifications in the WRF side. In the RegCM4, the received surface roughness is used to calculate air-sea transfer coefficients and fluxes over sea using Zeng ocean air-sea parameterization (Zeng et al., 1998). In this ~~implementation design~~, it is also possible to define a threshold for maximum roughness length (the default value is 0.02 m) and friction velocity (the default value is 0.02 m) in the configuration file of ~~atmospheric model component to ensure~~ RegCM4 to ensure the stability of the overall modeling system. The initial results to investigate the added value of atmosphere-wave coupling in the Mediterranean Sea can be found in Surenkok and Turuncoglu (2015).

2.4 River Routing Model (RTM)

To simulate the lateral freshwater fluxes (river discharges) at the land surface and to provide river discharge to ocean model component, the RegESM modeling system uses Hydrological Discharge (HD, version 1.0.2) model developed by Max Planck Institute (Hagemann and Dumenil, 1998; Hagemann and Lydia, 2001). The model is ~~basically~~ designed to run in a fixed global regular grid with 0.5° horizontal resolution ~~using daily time series of surface runoff and drainage as input fields~~. In this case, ~~model uses the model uses the~~ pre-computed river channel network to simulate the horizontal transport of the runoff within model watersheds using different flow processes such as overland flow, baseflow and riverflow. ~~In this case, the model integrated with driver uses a daily time step and requires daily time series of surface runoff and drainage as input fields.~~ The river routing model (RTM) plays ~~important an essential~~ role in the freshwater budget of the ocean model by closing the water cycle between the atmosphere and ocean model components. The original version of the model is slightly modified to support interaction with the coupled model components. To close water cycle between land and ocean, model retrieves surface and sub-surface runoff from ~~atmospheric component~~ the atmospheric component (RegCM or WRF) and provides estimated river discharge to the selected ocean model component (ROMS or MITgcm). In the current design of the driver, rivers can be represented in two different ways: ~~➤~~ (1) individual point sources that are vertically distributed to model layers, and ~~➤~~ (2) imposed as freshwater surface boundary condition like precipitation (P) or evaporation minus precipitation (E-P). ~~The model is also modified to write restart and output files directly in NetCDF (Network Common Data Form) format rather than using Max Planck Institute's SERVICE data type.~~ In this case, the driver configuration file is used to select the river representation type (1 or 2) for each river individually. The first option is preferred if river plumes need to be defined correctly by distributing river discharge vertically among the ocean model vertical layers. The second option is used to distribute river discharge to the ocean surface when there is a need to apply river discharge to a large areal extent close to the river mouth. In this case, a special algorithm implemented in NUOPC cap of ocean model components (ROMS and MITgcm) is used to find affected ocean model grids based on the effective radius (in km) defined in the configuration file of the driver.

2.5 The Driver: RegESM

The RegESM (version 1.1) is completely redesigned and improved version of the previously used and validated coupled atmosphere-ocean model (RegCM-ROMS) to study [the](#) regional climate of Caspian Sea and its catchment area (Turuncoglu et al., 2013). To simplify the design and to create more generic, extensible and flexible modeling system that aims to support easy integration of multiple model components and applications, the RegESM uses ~~driver-based model coupling~~ [a driver to implement the hub-and-spoke](#) approach. In this case, all the model components are combined using ESMF (version 7.1.0) framework to structure coupled ~~modelling-modeling~~ system. The ESMF framework is selected because of its unique online re-gridding capability, which allows the driver to ~~readily~~ perform different interpolation types ([i.e.,](#) bilinear, conservative~~etc.~~) over the exchange fields ([i.e.,](#) sea surface temperature, heat and momentum fluxes) and the ~~National Unified Operational Prediction Capability (NUOPC)~~ [NUOPC](#) layer. The NUOPC layer ~~basically simplifies component synchronization and run sequence by providing additional programming interface between coupled model and ESMF framework. It is a software layer built on top of the ESMF. It refines the capabilities of ESMF by providing a more precise definition of what it means for a model to be a component and how components should interact and share data in a coupled system.~~ The ESMF also provides the capability of transferring computational grids [in memory](#) among the model components, which has critical importance in the integration of the modeling system with [a](#) co-processing environment (see also Sect. 3). The RegESM ~~modelling-modeling~~ system also uses [ESMF and](#) NUOPC layer to support various configuration of component interactions such as defining multiple coupling time steps (~~fast and slow time steps; Fig. 2~~) among the model components ~~and explicit and semi-implicit type of model interaction (Fig. 3).~~ An example configuration of the four-component (ATM, OCN, RTM, and WAV) coupled modeling system can be seen in Fig. 2. In this case, the RTM component runs in a daily time step (slow) and interacts with ATM and OCN components, but ATM and OCN components can interact [each other](#) more frequently (~~i.e. 3 hours, fast~~) [such as every three hours](#).

The interaction ([also called as run sequences](#)) among the model components and driver are facilitated by the connector components provided by NUOPC layer. Connector components are mainly used to create [a](#) link between individual model components and driver. ~~The NUOPC layer also specifies an interface to define the model and connector. In this case, the number of active components and their interactions (also called as run sequences). To support different applications, interaction determines the number of connector component created in the modeling system. The interaction between model components can be in two way: (1) bi-directional such as atmosphere and ocean coupled modeling system or (2) unidirectional such as atmosphere and co-processing modeling system. In the uni-directional case, the co-processing component does not interact with the atmosphere model and only process retrieved information; thus there is one connector component.~~

The RegESM modeling system can be configured with two different type of time-integration scheme (coupling type) between [the](#) atmosphere and ocean components: ~~explicit and~~ [\(1\) explicit and \(2\) semi-implicit \(or leap-frog\)](#) (Fig. 3). In explicit type ~~of~~ coupling, two connector components (ATM-OCN and OCN-ATM direction) are executed at every coupling time step and model components start and stop at the same model time (Fig. [23a](#)). ~~Unlike, explicit coupling, a leap frog style interaction is supported between atmosphere and ocean components using semi-implicit type of model coupling. In this case, at every coupling time step. However,~~ the ocean model receives surface boundary conditions from the atmospheric model at one cou-

pling time step ahead of the current ocean model time in semi-implicit type coupling (Fig. 23b). The main advantage of using of the implicit and semi-implicit coupling aimed at lowering the overall computational cost of a simulation by increasing stability for longer coupling time steps. The main difference between the implicit and semi-implicit coupling is that it ensures the stability of the overall modeling system type is that the models interact on different time scales in implicit coupling scenarios.

5 As described earlier, the execution of the model components is mainly controlled by the driver. In this case, both Both sequential and concurrent execution of the model components are is allowed in the current version of the modeling system. If the model components and the driver are configured to run in sequence on the same set of PETs (Persistent Execution Threads), then the modelling modeling system executes in a sequential mode. This is mode is a much more efficient way to run the modeling system in case of limited computing resources. In the concurrent type of execution, the model components

10 run in mutually exclusive sets of PETs but the driver uses, but the NUOPC connector component uses a union of available computational resources (or PETs) of interacted model components. In By this way, the modelling modeling system can support a variety of computing systems ranging from local servers to large computing systems that could include high-speed performance networks, accelerators (i.e., Graphics Processing Unit or GPU) and parallel I/O capabilities. The main drawback of concurrent execution approach is to assign correct amount of computing resource to individual model components, which is not

15 a an easy task and might require a an extensive performance benchmark of a specific configuration of the model components, to achieve achieve best available computational performance. In this case, a load-balancing analysis of individual components and driver play a critical role in the performance of the overall modeling system. For example, LUCIA (Load-balancing Utility and Coupling Implementation Appraisal) tool can be used to collect all required information such as waiting time, the calculation time of each system components for a load-balancing analysis in the OASIS3-MCT based coupled system.

20 In general, the design and development of the coupled modeling systems involve a set of technical difficulties that arise due to the usage of the different computational grids in the model components. One of the most common examples is the mismatch between the land-sea masks of the model components (i.e., atmosphere and ocean models). In this case, the unaligned land-sea masks might produce artificial and/or unrealistic surface heat and momentum fluxes around the coastlines, narrow bays, straits and seas. The simplest solution of to this issue is to modify the land-sea masks of the individual model components manually to

25 align them. However, the main disadvantage of this solution is the required time and the difficulty to fix the land-sea masks of the different model components (especially when the horizontal grid resolution is high). In addition, same procedure must be repeated every time when Besides, the same procedure needs to be repeated whenever the model domain (i.e., shift or change in the model domain) or horizontal grid resolution is changed. As a result, this approach is considered as application specific and very time-consuming.

30 Unlike manual editing of the land-sea masks, customized interpolation techniques that also include extrapolation support might help helps to create more generic and automatized solutions. The RegESM modeling system uses extrapolation approach to overcome the mismatched land-sea mask problem for the interaction between atmosphere, ocean and wave components. To perform extrapolation, the driver uses a specialized algorithm (Fig. 4) to find the mapped and unmapped ocean grid points in the interpolation stage for every coupling direction (i.e. atmosphere-ocean, ocean-atmosphere, atmosphere-wave Fig. 4). According

35 to the algorithm, the mapped grid points have same land-sea mask type in both model components (i.e., both are sea or land).

On the other hand, the land-sea mask type does not match completely in the case of unmapped grid points ~~and they cannot be filled with the standard interpolation method such as bilinear interpolation.~~ The algorithm first interpolates the field from source to destination grid using grid points just over the sea and nearest-neighbor type interpolation (from Field_A to Field_B). In this case, ~~the two-step interpolation is performed to fill~~ if the source field (Field_A) belongs to the ATM component, then
5 ~~the nearest source to destination method is used.~~ In other cases, the interpolation performed using the nearest destination to source method. Similarly, the same operation is also performed by using bilinear type interpolation between the source and destination grids (from Field_A to Field_C). Then, the results of both interpolation (Field_B and Field_C) is compared to find mapped and unmapped grid points ~~and create a new modified mask for the exchange fields (Fig. 4).~~

After finding mapped and unmapped grid points, the exchange field can be interpolated from source to destination grid
10 ~~using two-step interpolation approach.~~ In the first step, exchange field is interpolated from source to destination grid ~~(i.e. from atmosphere to ocean) using grid points just over the sea (Fig. 4).~~ ~~using bilinear interpolation and the original land-sea mask.~~ Then, result field is used to fill unmapped grid points using nearest-neighbor type interpolation that is performed in the destination grid (from mapped grid points to unmapped grid points). One of the main ~~drawback~~ ~~drawbacks~~ of this method is that the result field might include unrealistic values and ~~for~~ sharp gradients in the areas of complex land-sea mask structure (i.e. ~~channels~~
15 ~~and/or straits)but this might~~, channels, straits). The artifacts around the coastlines can be fixed by applying a light smoothing after interpolation or using more sophisticated extrapolation techniques such as the sea-over-land approach (Kara et al., 2007; Dominicus et. al., 2014), which are not included in the current version of the modeling system. ~~In addition~~ ~~Also~~, the usage of ~~the~~ mosaic grid along with second-order conservative interpolation method, which gives smoother results when the ratio between horizontal grid resolutions of ~~the~~ source and destination grids are high, ~~might also help to solve the~~ ~~can overcome~~ unaligned
20 land-sea mask problem. ~~Fortunately, the next public~~ ~~The next major~~ release of ESMF ~~framework will supports higher order~~ ~~conservative interpolation as well as extrapolation~~ library (8.0) will include the creep fill strategy (Kara et al., 2007) to fill unmapped grid points.

3 Integration of RegESM ~~modeling system~~ Modeling System with ~~co-processing component~~ Co-processing Component

25 The newly designed modeling framework is ~~defined as~~ a combination of the ParaView co-processing plugin ~~and~~ which is called Catalyst (Fabian et. al., 2011) ~~and~~ ESMF library that is specially designed ~~to couple different earth system models for~~ ~~coupling different ESMs~~ to create more complex regional and global ~~modelling systems.~~

~~modeling systems.~~ In conventional co-processing enabled simulation systems (~~single physical model component such as~~ ~~atmosphere along with co-processing support~~), the Catalyst is used to integrate ParaView visualization pipeline ~~(defined as a~~
30 ~~Python script)~~ with the simulation code to support in-situ visualization through the use of ~~application specific~~ application-specific custom adaptor code ~~and~~ (Malakar et al., 2012; Ahrens et al., 2014; O'Leary et al., 2016; Woodring et al., 2016). A visualization pipeline integrates a data flow network in which computation is described as a collection of executable modules that are connected in a directed graph representing how data moves between modules (Moreland, 2013). There are three types of

modules in a visualization pipeline: sources (file readers and synthetic data generators), filters (transforms data), and sinks (file writers and rendering module that provide images to a user interface). The adaptor code ~~basically~~ acts as a wrapper layer and ~~transform~~ transforms information coming from ~~simulation code to the ParaView NUOPC cap to the co-processing component~~ in a compatible format that is defined using ParaView, Catalyst, and VTK (Visualization Toolkit) APIs. Moreover, the

5 adaptor code is responsible for defining the underlying computational grid and associating them with the multi-dimensional fields. After defining computational grids and fields, the ParaView processes the received data to perform co-processing to create desired products such as rendered visualizations, added value information (i.e., spatial and temporal averages, derived fields) ~~and/or writing raw model as well as writing raw~~ data to the ~~storage system~~ disk storage (Fig. 5a).

~~On the other hand, the~~ The implemented novel approach aims to create a more generic and standardized co-processing environment ~~specifically designed for earth~~ designed explicitly for Earth system science (Fig. 5b). By this approach, the existing ~~earth system models~~ ESMs, which are coupled with ESMF library using NUOPC interface, might benefit to use integrated modeling framework to analyze the data flowing from multi-component and multi-scale modeling system without extensive code development and restructuring. In this design, the adaptor code interacts ~~directly~~ with the driver ~~that is developed by using ESMF through the use of NUOPC cap~~ and provides an abstraction layer for the co-processing component. As discussed previously, the ESMF framework ~~basically uses~~ uses a standardized interface (initialization, run and finalize routines)

15 to plug new model components into ~~existing existing~~ modeling system such as RegESM in an efficient and optimized way. To that end, the new approach will benefit from the standardization of common tasks in the model components to integrate co-processing component with the existing modeling system. In this case, all the information (~~grid, field and their associated metadata information~~ grids, fields, and metadata associated with them) required by ParaView, Catalyst ~~plugin~~ is received from

20 the driver, and direct interaction between ~~individual other~~ model components and the ~~adaptor code~~ co-processing component is not allowed (Fig. 5b). The implementation logic of the adaptor code is very similar to the conventional approach (Fig. 5a) ~~but~~ However, in this case, it uses the standardized interface of the ESMF framework and NUOPC layer to define the computational grid and associated two and ~~for~~ three-dimensional fields of model components. The adaptor ~~basically maps the ESMF layer maps the~~ field (i.e., *ESMF_Field*) and grid (i.e., *ESMF_Grid*) objects to their VTK equivalents through the use of VTK

25 ~~API, which is and co-processing APIs, which are~~ provided by ParaView and co-processing plugin (Catalyst). Along with the usage of the new approach, the interoperability between simulation code and in-situ visualization system are enhanced and standardized. The new design also ensures easy to develop, extensible and flexible integrated modeling environment for earth Earth system science.

The development of the adaptor component plays ~~important an essential~~ role in the overall design and performance of the integrated modeling environment. The adaptor code mainly includes a set of functions for the initialization (defining computational grids and associated input ports), run and finalize the co-processing environment. Similarly, the ESMF framework also uses the same approach to plug new model components into the modeling system as ESMF components. In ESMF framework, the simulation code is separated into three ~~basic essential~~ components (initialization, run and finalize) and calling interfaces are triggered by the driver to control the simulation codes (i.e., atmosphere and ocean models). In this case, the initialization

35 phase includes definition and initialization of the exchange variables, reading input (initial and boundary conditions) and con-

figuration files and defining the underlying computational grid (step 1 in Fig. 6). The run phase includes a time stepping loop to run the model component in a defined period and continues until simulation ends (step 4 in Fig. 6). The time interval to exchange data between model and co-processing component can be defined using coupling time step just like the interaction among other model components. According to the ESMF convention, the model and co-processing components are defined as a gridded component while the driver is a coupler component. In each coupling loop, the coupler component prepares exchange fields according to the interaction among components by applying re-gridding ~~, performing (except coupling with co-processing component), performing a~~ unit conversion and common operations over the fields (i.e., rotation of wind field).

~~To allow interaction with the co-processing component~~ In the new version of the RegESM modeling system (1.1), the driver is extended to redistribute two and three-dimensional fields from physical model components ~~to allow interaction with the co-processing component~~. In the initialization phase, the numerical grid of ESMF components ~~are~~ is transformed into their VTK equivalents using adaptor code (step 3 in Fig. 6). In this case, *ESMF_Grid* object ~~can be~~ is used to create *vtkStructuredGrid* ~~and/or vtkUnstructuredGrid~~ along with their modified parallel two-dimensional decomposition configuration, which is supported by ESMF/NUOPC grid transfer capability ~~. The simplified diagram of the ESMF/NUOPC grid transfer feature is also shown in (Fig. 7. In this case).~~ According to the design, each model component transfers their numerical grid representation to co-processing component at the beginning of the simulation (step 1 in Fig. 6) while assigning independent two-dimensional decomposition ratio to the retrieved grid definitions. ~~In the example configuration, the atmosphere model with 2x3 decomposition ratio (in x and y direction) is mapped to 2x2 in co-processing component (Fig. 7). COP component.~~ Similarly, the ocean model transfers its numerical grid with 4x4 decomposition ratio to co-processing component with 2x2 (Fig. 7). ~~The In this case, ATM and OCN model components do not need to have the same geographical domain. The only limitation is that the domain of ATM model component must cover the entire OCN model domain for an ATM-OCN coupled system to provide the surface boundary condition for OCN component. The~~ main advantage of the generic implementation of the driver component is to assign different computational resources to ~~both model and co-processing components. By this design, the~~ the components. The computational resource with accelerator support (GPU~~etc.~~) can be independently used by co-processing component to ~~process (do rendering (i.e., iso-surface extraction, volume rendering, texture mapping etc.) and texture mapping) and processing~~ the high volume of data in an efficient and optimized way. The initialization phase is also responsible ~~to define for defining~~ exchange fields that will be ~~exchanged-transferred~~ among the model components and maps *ESMF_Field* representations ~~defined in physical model components to as~~ vtkMultiPieceDataSet objects in co-processing component ~~-(step 2-3 in Fig. 6)~~. Due to the modified two-dimensional domain decomposition structure of the numerical grids of the simulation codes, the adaptor code also modifies the definition of ghost regions ~~that are defined as~~ a small subset of the global domain that ~~are~~ is used to perform numerical operations around edges of the decomposition elements. In this case, the ghost regions (or halo regions in ESMF convention) are updated by using specialized calls, and after that, the simulation data are passed (as *vtkMultiPieceDataSet*) to the co-processing component. During the simulation, the co-processing component of the modeling system also synchronizes with the simulation code and retrieves updated data (step 5 in Fig. 6) to process and analyze the results (step 6 in Fig. 6). The interaction between driver and the adaptor continues until the simulation ends (step 4, 5 and 6 in Fig. 6) and the driver continues

to redistribute the exchange fields using *ESMF_FieldRedist* calls. The ~~driver~~NUOPC cap of model components also supports vertical interpolation of the three-dimensional exchange fields to height (from ~~s-coordinates of ROMS ocean~~terrain-following coordinates of RegCM atmosphere model) or depth coordinate (from ~~sigma-coordinates of RegCM atmosphere~~s-coordinates of ROMS ocean model) before passing information to the co-processing component (COP). Then, finalizing routines of the model and co-processing components are called to stop the model simulations and the data analysis pipeline that destroy the defined data structure/s and free the memory (step 7-8 in Fig. 6).

4 Use Case and Performance Benchmark

To test the capability of the newly designed integrated modeling system that is described briefly in the previous section, the three components (atmosphere, ocean, and co-processing) configuration of RegESM 1.1 modeling system is implemented to analyze category 5 Hurricane Katrina. Hurricane Katrina was the costliest natural disaster and has been named one of the five deadliest hurricanes in the history of the United States, and the storm is currently ranked as the third most intense United States land-falling tropical cyclone. After established in the southern Florida coast as a weak category 1 storm near 22:30 UTC 25 August 2005, it strengthened to a category 5 storm by 12:00 UTC 28 August 2005 as the storm entered the central Gulf of Mexico (GoM). ~~To observe the evolution of the Hurricane Katrina and understand importance of air-sea interaction in terms of its development and predictability, the~~The model simulations are performed between 27-30 Aug. 2005, which is the most intense period of the cyclone, for three days to observe the evolution of the Hurricane Katrina and understand the importance of air-sea interaction regarding its development and predictability. The next section mainly includes detailed information of three components configuration of the modeling system as well as used computing environment, the preliminary benchmark results that are done in limited computing resource (without GPU support) and analysis of the evolution of Hurricane Katrina.

4.1 Working Environment

The model simulations and performance benchmarks are done on a cluster (SARIYER) provided by the National Center for ~~High-Performance~~High-Performance Computing (UHeM) in Istanbul, Turkey. The CentOS 7.2 operating system installed in compute nodes are configured with a two Intel Xeon CPU E5-2680 v4 (2.40GHz) processor (total 28 cores) and 128 GB RAM. In addition to the compute nodes, the cluster is connected to a high-performance parallel disk system (Lustre) with 349 TB storage capacity. The performance network, which is based on Infiniband FDR (56 Gbps) is designed to give the highest performance for the communication among the ~~compute~~ servers and the disk system. Due to the lack of GPU accelerators in the entire system, the in-situ visualization integrated performance benchmarks are done with the support of software rendering provided by Mesa library. Mesa is an ~~open-source~~open-source OpenGL implementation that supports a wide range of graphics ~~hardwares~~hardware each with its ~~own~~ back-end called a renderer. Mesa also provides several software-based renderers for use on systems without graphics hardware. In this case, ParaView is installed with Mesa support to render information without using hardware-based accelerators.

4.2 Domain and Model Configurations

The ~~regional-earth-system-model~~ Regional Earth System Model (RegESM 1.1) is configured to couple atmosphere (ATM; RegCM) and ocean (OCN; ROMS) models with newly introduced ~~novel~~ in-situ visualization component (COP; ParaView Catalyst version 5.4.1) to analyze the evolution of Hurricane Katrina and to assess the overall performance of the modeling system. In this case, two atmospheric model domains were designed for RegCM simulations using one-way nesting approach, as shown in Fig. 8. The outer atmospheric model domain (low-resolution; LR) with a resolution of 27-km is centered at 77.5°W, 25.0°N and covers almost entire the United States, the western part of Atlantic Ocean and north-eastern part of Pacific Ocean for better representation of the ~~large-scale~~ large-scale atmospheric circulation systems ~~and~~. The outer domain is enlarged as much as possible to minimize the effect of the lateral boundaries of the atmospheric model in the simulation results of the inner model domain (high-resolution; HR). The horizontal grid spacing of ~~second-inner~~ domain is 3-km and covers the entire GoM and the western Atlantic Ocean to provide ~~high-resolution~~ high-resolution atmospheric forcing for coupled atmosphere-ocean model simulations and perform ~~cloud-resolving~~ cloud-resolving simulations. Unlike the outer domain, the model for the inner domain is configured to use the non-hydrostatic dynamical core (available in RegCM 4.6) to allow better representation local scale vertical acceleration and ~~important~~ essential pressure features.

15 The lateral boundary condition for the outer domain is obtained from European Centre for Medium-Range Weather Forecasts (ECMWF) latest global atmospheric reanalysis (ERA-Interim project; Dee et. al., 2011), which is available at 6-h intervals at a resolution of 0.75°x0.75° in the horizontal and 37 pressure levels in the vertical. On the other hand, the lateral boundary condition of the HR domain ~~, which is used in the fully coupled model simulations, is~~ is specified by the results of the LR domain. Concerning cumulus convection, Massachusetts Institute of Technology-Emanuel convective parameterization scheme

20 (MIT-EMAN; Emanuel, 1991; Emanuel and Zivkovic-Rothman, 1999) is used in outer model simulations. Along with selected cumulus convection parameterization, sub-grid explicit moisture (SUBEX; Pal et al., 2000) scheme is used to represent large-scale precipitation for LR domain.

As it ~~also shown can be seen~~ in Fig. 8, the ROMS ocean model is configured to cover entire the GoM to allow better tracking of the Hurricane Katrina. In this case, the used ocean model configuration is very similar to the configuration used by Physical

25 Oceanography Numerical Group (PONG), Texas A&M University (TAMU), in which the original model configuration can be ~~accessible~~ accessed from their THREDDS server. The ocean model has a spatial resolution of 1/36°, which corresponds to a non-uniform resolution of around 3 km (655 x 489 grid points) with highest grid resolution in the northern part of the domain. The model has 60 vertical sigma layer ($\theta_s = 10.0$, $\theta_b = 2.0$) to provide detailed representation of the main circulation pattern of the region and vertical tracer gradients. The bottom topography data of the GoM is constructed using the ETOPO1 dataset

30 (Amante and Eakins, 2009), and minimum depth (h_c) is set to 400 m. The bathymetry data are also modified so that the ratio of depths of any two adjacent grids does not exceed 0.25 to enhance the stability of the model and ensure hydrostatic consistency creation that prevents pressure gradient error. The Mellor-Yamada level 2.5 turbulent closure (MY; Mellor and Yamada, 1982) is used for vertical mixing, while rotated tensors of the harmonic formulation are used for horizontal mixing. The lateral

boundary conditions for ROMS ocean model are provided by Naval Oceanographic Office Global Navy Coastal Ocean Model (NCOM) during 27-30 August 2005.

The model coupling time step between atmosphere and ocean model component is set to 1 hour but 6 minutes coupling time step is used to provide one-way interaction with co-processing component to study Hurricane Katrina in a very high temporal resolution. In the coupled model simulations, ~~that use same configuration of~~, the ocean model ~~but different resolution of the atmospheric model component, the SST data provided~~ provides SST data to the atmospheric model in the region where their numerical grids overlap. In the rest of the domain, the atmospheric model uses SST data provided by ERA-Interim dataset (prescribed SST). The results of the performance benchmark also include additional tests with smaller coupling time step such as 3 minutes for the interaction with the co-processing component. In this case, the model simulations for the analysis of ~~the~~ Hurricane Katrina runs over three days, but only one day of simulation length is chosen in the performance benchmarks to reduce ~~amount of used computing resources~~ the compute time.

4.3 Performance Benchmark

~~To~~ A set of simulations are performed with different model configurations to assess the overall performance of the coupled modeling system by focusing overhead of the newly introduced co-processing component, ~~a set of simulations are performed with different model configurations~~ (Table 1). The performance benchmarks include analysis of the extra overhead provided by the co-processing component, coupling interval between physical models and co-processing component under different rendering load such as various visualization pipelines (Table 1). ~~To scale up to large number of processors, two~~ Two different atmospheric model configurations ~~are defined~~ (a low-resolution, LR and high-resolution HR) are defined to scale up to a large number of processors. The LR model domain includes around 900,000 grid points in the atmospheric model while the HR domain contains 25 million grid points. In both ~~ease cases~~, the ocean model configuration is ~~same~~ the same, and it has around 19 million grid points. ~~Beside~~ Besides the change of the dynamical core of atmospheric model component in HR case (non-hydrostatic), the rest of the model configurations are preserved. To isolate the overhead of the driver from the overhead of the co-processing component, first individual model components (ATM and OCN) are run in standalone mode and then, the ~~best scaled model configurations in terms of~~ best scaled model configurations regarding two-dimensional decomposition configuration are used in the coupled model simulations (CPL and COP). Due to the current limitation in the integration of the co-processing component, the coupled model only supports sequential type execution (see ~~section 2.5~~ Section 2.5 for more information) when the co-processing component is activated, but this limitation will be removed in the future version of the modeling system (RegESM 2.0). As mentioned in the previous section, the length of the simulations ~~are is~~ kept relatively short (1 day) in the benchmark analysis to perform many simulations with different model configurations (~~coupling interval etc.~~ i.e., coupling interval, visualization pipelines and domain decomposition parameters).

The benchmark results of standalone model components (ATM and OCN) can be seen in Fig. 9. In this case, two different atmospheric model configurations are considered to see the effect of the domain size and non-hydrostatic dynamical core in the benchmark results (LR and HR; Fig. 8). The results show that the model scales pretty well and it is clear that the HR case shows better scaling results than LR configuration of the atmospheric component (ATM) as expected. It is also shown that

around 588 processors, which is the highest available compute resource, the communication among the processors dominate the benchmark results and even HR case does not gain further performance (Fig. 9a). Similar to the atmospheric model component, the ocean model (OCN) is also tested to find the best two-dimensional domain decomposition configuration (tiles in x and ~~y~~ direction-y-direction). As it can be seen from the Fig. 9b, the selection of the tile configuration affects the overall performance of the ocean model. In general, model scales better if tile in ~~x-direction-the x-direction~~ is bigger than tile in ~~y-direction-the y-direction~~, but this is more evident in the small number of processors. ~~This~~ The tile effect in the results is mainly due to the memory management of Fortran programming language (column-major order) as well as the total number of active grid points (not masked as land) placed in each tile. On the other hand, the tile options must be selected carefully while considering the dimension of the model domain in each direction. In some tile configuration, it is not possible to run the model due to the used underlying numerical solver and the required minimum ghost points. To summarize, the ocean model scales well until 588 cores with the best tile configurations ~~shown-indicated~~ in Fig. 9b.

~~Using the benchmark results of standalone atmosphere and ocean models, the~~ The performance of the two-component modeling system (CPL) can be investigated using the benchmark results of the standalone atmosphere and ocean models. In this case, the best two-dimensional decomposition parameters of the standalone ocean model simulations are used in the coupled model simulations (Fig. 9b). The comparison of the standalone and coupled model simulations show that the driver component introduces additional 5-10% (average is 5% for LR and 6% for HR cases) overhead in the total execution time, which slight increases along with the used total number of processors, which is acceptable when increased number of MPI communication between the components are considered (Fig. 9 and 10a-ba). The extra overhead is mainly due to the interpolation (sparse matrix multiply performed by ESMF) and extrapolation along the coastlines to match land-sea masks of the atmosphere and ocean models and fill the unmapped grid points to exchange data (Fig. 4).

To investigate the overhead introduced by the newly designed co-processing component, the three-component modeling system (COP) is tested with three different visualization pipelines (P1, P2, and P3; Table 1) using two different atmospheric model configurations (LR and HR) and coupling interval (3 and 6 minutes with co-processing). In this case, the measured total execution time during the COP benchmark results also includes vertical interpolation (performed in ESMF cap) to map data from sigma coordinates to height (or depth) coordinates for both physical model components (ATM and OCN). As shown in Fig. 10a-bb-d, the co-processing components require 10-40% extra execution time for both LR and HR cases depending on used visualization pipeline when it is compared with CPL simulations. The results also reveal that the fastest visualization pipeline is P3 and the slowest one is P1 for the HR case (Fig. 10b and d). Table 1 also includes the execution time of the single visualization pipeline (measured by using *MPI_Wtime* call) isolated from the rest of the tasks. In this case, each rendering task gets 2-4 seconds for P1 and P2 cases and 7-15 seconds for the P3 case in LR atmospheric model configuration. For HR case, P1 and P2 ~~takes-take~~ around 17-80 seconds~~and-~~, and the P3 case is rendered in around 8-10 seconds. These results show that the time spent in co-processing component (~~basically~~ sending data to ParaView, Catalyst, and rendering to create the output) fluctuates too much and do not show predictable, stable behavior. ~~This-It~~ might be due to the ~~special-particular~~ configuration of the ParaView, which is configured to use software-based rendering to process data in CPUs and load in the used high-performance computing system (UHeM) even if the benchmark tests are repeated multiple times.

In addition to the testing ~~modelling~~ modeling system with various data processing load, a benchmark with increased coupling time step is also performed (see P23M in Fig. 10~~b~~c). In this case, the coupling time step between physical model components and the co-processing component is increased (from 6 minutes to 3 minutes) to produce output in doubled frame rate, but coupling interval between physical model components (ATM and OCN) are kept same (1 ~~hours~~hour). The benchmark results show that increased coupling time step also rises overhead due to the co-processing from 45% to 60% for HR case and pipeline P2 when it is compared with the results of two-component simulations (CPL; Fig. 10~~b~~a). It is also shown that the execution time of co-processing enabled coupled simulations increase but the difference between P2 and P23M cases are reduced from 66% to 37% when ~~number of processor~~ the number of processors increased from 140 to 588.

~~Besides the~~ In addition to the analysis of timing profiles of modeling system under different rendering load, the amount of data exchanged and used in the in-situ visualization case can be compared with the amount of data that would be required for offline visualization at the same temporal frequency to reveal the added value of the newly introduced co-processing component. For this purpose, the amount of data exchanged with co-processing component is given in Table 1 for three different visualization pipelines (P1, P2, and P3). In co-processing mode, the data retrieved from model components (single time step) through the use of the driver read from memory and passed to the ParaView, Catalyst for rendering. Besides, processing data concurrently with the simulation on co-processing component, the offline visualization (post-processing) consists of the computations that are done after the model is run and requires to store numerical results in a disk environment. For example, 3-days long simulation with 6-minutes coupling interval produces around 160 GB data (720 time-step) just for a single variable from high-resolution atmosphere component (P1 visualization pipeline) in case of using offline visualization. In the case of using co-processing, the same analysis can be done by applying same visualization pipeline (P1), which requires to process only 224 MB data stored in the memory, in each coupling interval. Moreover, storing results of three-day long, high-resolution simulation of RegCM atmosphere model (in netCDF format) for offline visualization requires around 1.5 TB data in case of using 6-minutes interval in the default configuration (7 x 3d fields and 28 x 2d fields). It is evident that the usage of co-processing component reduces the amount of data stored in the disk and allows more efficient data analysis pipeline.

~~Besides the~~ minor fluctuations in the benchmark results, the ~~modelling~~ modeling system with co-processing component scales pretty well to the higher number of processors (or cores) without any ~~major~~ significant performance pitfalls in the current configuration. On the other hand, the usage of accelerator enabled ParaView configuration (i.e., using NVIDIA EGL library) and ParaView plugins with accelerator support such as NVIDIA IndeX volume rendering plugin and new VTK-m filters to process data on GPU will ~~definitely~~ improve the benchmark result. The NVIDIA IndeX for ParaView Plugin ~~basically~~ enables large-scale and high-quality volume data visualization capabilities of the NVIDIA IndeX library inside the ParaView and might help to reduce time to process high-resolution spatial data (HR case). ~~This will be investigated future when~~ In addition to NVIDIA IndeX plugin ~~supports in-situ visualization under ParaView. In addition, the~~ VTK-m is a toolkit of scientific visualization algorithms for emerging processor architectures such as GPUs (Moreland, 2016). The model configurations used in the ~~benchmark~~ simulations also write simulation results to the disk in netCDF format. In case of disabling of writing data to disk or configure the models to write data with large time intervals (i.e., monthly), the simulations with active co-processing

component will run much faster and make the analysis of the model results in real time efficiently especially in live mode (see Section 5.1).

5 ~~Results~~Demonstration Application

~~As it indicated in the previous sections, the newly designed modelling system is able to~~The newly designed modeling system
can analyze numerical simulation results in both in-situ (or live) and co-processing ~~(or post-processing) mode and this mode.~~
In this case, a Python script, that defines the visualization pipeline, mainly controls the selection of the operating mode and is
generated using ParaView, co-processing plugin. The user could also activate live visualization mode, just by changing a single
10 line of code (need to set `coprocessor.EnableLiveVisualization` as True) in Python script. This section aims to give more detailed
information about two different approaches by evaluating numerical simulation of Hurricane Katrina in both ~~mode~~models to
reveal the designed ~~modelling~~modeling system capability and its limitations.

5.1 Live Visualization Mode

While the live visualization designed to examine the simulation state at a specific point in time, the temporal filters such as
15 ParticlePath, ParticleTracer, TemporalStatistics that are designed to process data using multiple time steps cannot be used in
this mode. However, live visualization mode allows ~~to connect to~~connecting to the running simulation anytime through the
ParaView GUI in order to make detailed analysis by modifying existing visualization pipelines defined by a Python script.
In this case, the numerical simulation can be paused while the visualization pipeline is modified and continue to run with
the revised one. It is ~~oblivious~~evident that the live visualization capability gives ~~a~~-full control to the user to make further
20 investigation about the simulation results and facilitate better insight into the underlying physical process and its evolution in
time.

The current version of the co-processing enabled modeling system ~~is able to~~can process data of multiple model components
by using multi-channel input port feature of ParaView Catalyst. In this case, each model has two input channels based on
the rank of exchange fields. For example, atmospheric model component has *atm_input2d* and *atm_input3d* input channels
25 to make available processing both two and three-dimensional exchange fields. The ~~underlying ESMF adaptor resides in the~~
~~driver side and~~underlying adaptor code resides between the NUOPC cap of co-processing component and ParaView, Catalyst
and provides two grid definitions (2d and 3d) for each model components for further analysis. In this design, the ParaView
Co-processing Plugin is used to generate Python co-processing scripts~~and user need~~, and user needs to map data sources to
input channels by using predefined names such as *atm_input2d* and *ocn_input3d*. Then, adaptor provides the required data to
30 co-processing component through each channel to perform rendering and data analysis in real time. The fields that are used in
the co-processing component are defined by generic ASCII formatted driver configuration file (*exfield.tbl*), which is also used to
~~exchange data among physical~~define exchange fields among other model components such as atmosphere and ocean models.
Fig. 11 shows a screenshot of live visualization of three-dimensional relative humidity field provided by the low-resolution

atmospheric model component, underlying topography information, and vorticity of ocean surface that is provided by ocean model component.

5.2 Co-processing Mode

In addition to live visualization ~~model mode~~ that is described briefly in the previous section, ParaView Catalyst also allows to ~~process-render~~ and store data using predefined co-processing pipeline (in Python) for further analysis. Co-processing mode can be used for ~~two purposes:~~ 1) three purposes: (1) the simulation output can be directed to the co-processing component to ~~calculate-render data in batch mode and write image files to the disk,~~ (2) added value information ~~such as (i.e.,~~ vorticity from wind components ~~or,~~ eddy kinetic energy from ocean current) can be calculated and stored in a disk for further analysis and ~~2) (3)~~ storing simulation output in a higher temporal resolution to process it later (post-processing) or create a representative dataset that can be used to ~~create-design~~ visualization pipeline for co-processing or live visualization modes. In this case, the newly designed ~~modelling system is able to-~~ modeling system can apply multiple visualization and data processing ~~pipeline-pipelines~~ to the simulation results at each coupling time step to make a different set of analysis ~~in-the-over the~~ results of same numerical simulation for more efficient data analysis. The ~~modelling-modeling~~ system also facilitates multiple input ports to process data flowing from multiple ~~earth-system-model-ESM~~ components. In this design, input ports are defined automatically by co-processing component based on activated ~~physical~~ model components (ATM, OCN, etc.) and each model components have two ports to handle two and three-dimensional grids (and fields) separately such as *atm_input2d*, *atm_input3d*, *ocn_input2d* and *ocn_input3d*.

To test the capability of the co-processing component, the evolution of Hurricane Katrina is investigated by using two different ~~configuration-of~~ configurations of the coupled model (COP_LR and COP_HR) that are also used to analyze the overall computational performance of the ~~modelling-modeling~~ system (see Section 4.3). In this case, both model configuration uses the same configuration of OCN model component ~~but,~~ but the different horizontal resolution of the ATM model is considered (27 km for LR and 3 km for HR cases).

Figure 12 shows 3-hourly snapshots of the model simulated clouds that are generated by processing three-dimensional relative humidity field calculated by the low-resolution version of the coupled model (COP_LR) using NVIDIA IndeX volume rendering plugin as well as ~~stream-lines-streamlines~~ of Hurricane Katrina, which is calculated using three-dimensional wind field. The visualization pipeline also includes sea surface height and surface current from the ocean model component to make an integrated analysis of the model results. Figure 12a-b shows the streamlines that are produced by extracting the hurricane using ParaView *Threshold* filter. In this case, extracted region is used as a seed to calculate backward and forward streamlines. In Figure 12c-e, sea surface height, sea surface current and surface wind vectors (10-meters) are shown together to give insight about ~~interaction of ocean-related variables with-~~ the interaction of ocean-related variables with the atmospheric wind. Lastly, the hurricane reaches to the land and start to disappear due to increased surface roughness and lack of energy source (Fig. 12f). While ~~low-resolution~~ of atmosphere model configuration is used, the information produced by the new modeling system enabled to investigate the evolution of the hurricane in a very high temporal resolution, which was impossible before. A day-long animation that is also used to create Figure 12 can be found as a supplemental video ([Turuncoglu, 2018a](#)).

35 In addition to the analysis of ~~low-resolution~~low-resolution model results to reveal the evolution of the hurricane in a very high temporal resolution, low and high-resolution model results are also compared to see the added value of the increased horizontal resolution of the atmospheric model component ~~in terms of regarding~~ representation of the hurricane and its structure. To that end, a set of visualization pipelines are designed to investigate the vertical updraft in the hurricane, simulated track, precipitation pattern, and ocean state. In this case, two time snapshots are considered: ~~→(1)~~→(1) 28 August 2005 0000 UTC,

5 when it is the early stage of the hurricane in Category 5 and ~~→(2)~~→(2) 29 August 2005 0000 UTC when it is just before Katrina makes its third and final landfall near ~~the~~-Louisiana–Mississippi border, where the surface wind is ~~very strong~~powerful, and surface currents had a strong onshore component (McTaggart-Cowan et al., 2007a, b). In the analysis of vertical structure, the hurricane is isolated based on the criteria of surface wind speed that exceeds 20 ~~m/s~~ms⁻¹ and the seed (basically set of points ~~in-defined as vtkPoints~~data-type) ~~input~~) for ParaView *StreamTracerWithCustomSource* filter are defined dynamically

10 using *ProgrammableFilter* as a circular plane with a radius of 1.2° and points distributed with 0.2° interval in both direction (x and y) around the center of mass of the isolated region. Then, forward and backward streamlines of vorticity are computed separately to see inflow at low and mid levels and outflow at upper levels for both low (COP_LR; Fig. 13a, b, d and e) and high-resolution (COP_HR; Fig. 14a, b, d and e) cases. The analysis of simulations reveal that the vertical air movement shows higher spatial variability in high-resolution simulation (COP_HR) case even if the overall structure of the hurricane is similar

15 in both cases. As it is expected, the strongest winds occur in a region formed as a ring around the eyewall of the hurricane, which is the lowest surface pressure occurs. In addition, the analysis of cloud liquid water content also shows that low and mid-levels of the hurricane have higher water content in a decreasing trend with height and spatial distribution of precipitation is better represented in high resolution case (Fig. 14a-b and d-e), which is consistent with the previous modelling study of Trenberth et al. (2007). It is also seen that the realistic principal and secondary precipitation bands around the eye of the

20 hurricane are more apparent and well structured in the high-resolution simulation while low-resolution case does not show those ~~small-scale~~small-scale features (Fig. 13a-b and d-e). In addition to the analysis of the atmospheric model component, the loop current, which is a warm ocean current that flows northward between Cuba and the Yucatan Peninsula and moves north into the Gulf of Mexico, loops east and south before exiting to the east through the Florida Straits and joining the Gulf Stream, is well defined by the ocean model component in both cases (Fig. 13c and f; Fig. 14c and f). The track of the hurricane is also

25 compared with the HURDAT2 second-generation North Atlantic (NATL) hurricane database, which is the longest and most complete record of tropical cyclone (TC) activity in any of the world's oceans (Landsea and Franklin, 2013). In this case, the eye of the hurricane is extracted as a region that surface pressure anomaly is greater than 15 ~~mb~~millibar (shown as a circular region near the best track). As it can be seen from figures, Katrina move over in the central Gulf, which is mainly associated with the loop current and persistent warm and cold eddies, and intensified as it passed over the region due to the high ocean

30 heat content in both simulation (Fig. 13c and f and Fig. 14c and f). The comparison of the low and high-resolution simulations also indicate that the diameter of hurricane-force winds at peak intensity is bigger in high-resolution simulation case at 29 August 2005 0000 UTC (Fig. 13f and Fig. 14f). An animation that shows the comparison of low and high-resolution model results can be found as a supplemental video (Turuncoglu, 2018b).

While the main aim of this paper is to give design details of the new in-situ visualization integrated modeling system and show its capability, the performance of the coupled modeling system to represent one of the most destructive ~~hurricane~~ hurricanes is very satisfactory especially for high-resolution case (COP_HR). Nonetheless, the individual components (atmosphere and ocean) of the modeling system can be tuned to have better agreement with the available observations and previous studies. Specifically for the analysis of the hurricane, a better storm tracking algorithm ~~need~~-needs to be implemented using ParaView *Programmable Filter* by porting existing legacy Fortran codes for more accurate storm tracking in both live and co-processing mode.

6 Discussion of The Concepts Associated with Interoperability, Portability, and Reproducibility

In the current design of the RegESM modeling system, the NUOPC cap of the co-processing component is designed to work with regional modeling applications that have specific horizontal grid (or mesh) types such as rectilinear and curvilinear grids. Therefore, the newly introduced co-processing interface (NUOPC cap and adaptor code) need to be generalized to be compatible with other regional and global modeling systems coupled with ESMF and NUOPC layer. Specifically, the following issues need to be addressed to achieve better interoperability with existing modeling systems and model components: (1) redesigning the NUOPC cap of the newly introduced co-processing component to support various global and regional mesh types such as Cubed-Sphere and unstructured Voronoi meshes, (2) extending the adaptor code to represent mesh and exchange fields provided by NUOPC cap using VTK and ParaView Catalyst APIs, (3) adding support to co-processing interface for models with online nesting capability, and (4) adding support to have common horizontal grid definition in co-processing component to make integrated analysis of data (i.e., calculating air-sea temperature difference and correlation) produced by various model components. Moreover, the co-processing interface can be tightly integrated with the NUOPC layer to provide a simplified API for designing new in-situ visualization integrated modeling systems in an efficient and standardized way. Besides, addressing issues of interoperability, supporting different modeling systems and their applications to create a more generic in-situ visualization solution, the RegESM modeling system is also tested with different model configurations such as coupling RegCM, MITgcm, and co-processing component to investigate air-sea interaction in the Black Sea basin. The initial results show that the co-processing component can also process data flowing from different model configuration supported by RegESM rather than the configuration used in this study.

When the diverse nature of high-performance computing systems, their hardware infrastructure (i.e., performance networks and storage systems) and software stacks (i.e., operating systems, compilers, libraries for inter-node communication and their different versions) are considered, realizing fully portable modeling system becoming increasingly crucial for the scientific community. In this case, the detailed examination of possible configurations of the modeling system and exiting computing environments can help to improve the flexibility and portability of the developed modeling system. Specifically for RegESM modeling system, the use case application and benchmark simulations reveal that the single executable approach (combines all model components into one program) used in the design of the modeling system can cause a portability problem when visualization and simulation run on concurrent resources. In the case of a homogeneous computing environment (all nodes with

or without GPU support), the in-situ enabled modeling system runs without any particular problem because each MPI (Message Passing Interface) processes have access to the same software and hardware resources. In contrast to the homogeneous computing environment, the computing system does not have a uniform view of underlying hardware and software stack (i.e., mixed servers with and without GPU support) in a heterogeneous computing environment. As a result, the simulation with in-situ visualization support fails due to missing shared software libraries specific to underlying GPU in all used nodes or servers. In this case, two approaches can be used to overcome the problem: (1) installation of required libraries to the entire system even servers do not have GPU support, and (2) restructuring modeling system to support two executable, one for co-processing and one for physical model components. The second approach is considered a more generic and flexible solution and enhances the portability of the modeling system. It also allows implementing a loosely coupled in-situ visualization system and enables the use of specialized hardware (GPU and more memory) for rendering (Rivi et al., 2012). The main drawback of the loosely coupled in-situ visualization approach is that it requires transferring data over the network. As a result, the network performance can be a bottleneck for the modeling system, especially for high-resolution multi-component modeling applications.

When the complexity of regional and global ESMs are considered, developing fully reproducible, and portable modeling system (i.e., RegESM) is a challenging task and requires significant human interaction to keep track of detailed metadata and provenance information about the model, simulation and computing environment (in both software and hardware level). The use of scientific workflows in earth system science has demonstrated advantages in terms of metadata, provenance, error handling, and reproducibility in an automatized and standardized way (Turuncoglu et al., 2011, 2012; Turuncoglu, 2012). Additionally, the rapid development in the software container technology can help to design flexible and portable computing environment for earth system modeling. Hence, the Docker container has been implemented to examine the feasibility of using the container approach for newly developed in-situ visualization integrated modeling system (RegESM). A container is a standard unit of software that helps to create a package for software and all its dependencies. By this way, the application can be ported from one computing environment to another without worrying underlying hardware infrastructure and software stack. It also enhances the numerical reproducibility of simulation results by creating a standardized computing environment isolated from the dependencies. In this study, the Docker is selected as a container environment because it is widely adopted across the software industry and has a very active user community. Despite the flexibility and easy to use nature of the Docker containers, using specialized hardware such as NVIDIA GPUs, which require kernel modules and user-level libraries to operate, is not supported natively. In this case, Docker container cannot access the underlying GPU resource to perform hardware level rendering for in-situ visualization. To enable portable GPU-based containers, NVIDIA developed a special container that mounts the user mode components of the driver and the GPUs into the container at launch. As a part of this study, the newly developed RegESM modeling system tested with both Docker (software rendering through the use of Mesa library) and NVIDIA Docker (hardware based rendering) to evaluate the potential of using container technology to improve portability and reproducibility of the RegESM modeling system. The initial results show that the developed modeling system can take advantage of the container approach to create portable and reproducible modeling system in both in-situ and co-processing modes without considerable performance loss (5-10%). The added value of using NVIDIA Docker is that it enables to utilize

the underlying GPU resource to perform rendering (i.e., representation of clouds using direct volume rendering method). More information about the creating Docker container for in-situ visualization enabled modeling system can be found in dedicated GitHub repository (see code availability section).

7 Summary and Conclusions

5 In this study, the newly developed state-of-art in-situ visualization integrated modeling system (RegESM 1.1) is used to demonstrate the feasibility and added value of the integrated modeling environment to analyze the high volume of data coming from multi-component ~~earth system model~~ ESM in an integrated way, which was not possible before. In this case, ParaView, Catalyst ~~plugin~~ is used as a co-processing component to process and render data. The results of the selected use case (evolution of Hurricane Katrina) show that the co-processing component provides easy to use and generic modeling and data analysis environment, which is independent ~~from of~~ the underlying physical model components used. Moreover, it promotes the usage of co-processing capability with the existing ~~earth system models~~ ESMs, which is coupled using ESMF framework and NUOPC layer, without ~~major significant~~ code restructuring and development and help to increase the interoperability between ~~earth system models~~ ESMs and ParaView, ~~Catalyst in-situ visualization plugin~~ co-processing plugin (Catalyst). In the current implementation, the prototype version of ~~adaptor code basically acts as a wrapper or~~ the adaptor code acts as an abstraction layer to
15 simplify and standardize the regular tasks to integrate the simulation code with in-situ visualization and analysis environment. The driver is also responsible ~~to redistribute for redistributing~~ the data to co-processing component while preserving its numerical grid along with the support of vertical interpolation. The coupling of co-processing component with the generic driver ~~facilitate facilitates~~ to define custom data processing pipelines (defined by ~~special~~ Python scripts) easily and allows integrated analysis of data originated from different components (i.e., atmosphere and ocean models) of the RegESM modeling system in
20 a very high temporal resolution. In this way, RegESM modeling system can be used to study various physical processes (i.e., extreme precipitation events, air-sea interaction, convection, and turbulence) that could not be analyzed with the conventional post-processing approaches.

While the results of the in-situ visualization integrated modeling system are encouraging, the co-processing component will be extended to support different regional and global computational grid representations supported by ESMF library such as
25 unstructured meshes for having a generic adaptor for various model applications. Additionally, we are currently exploring:
~~1)~~ (1) the way to optimize the grid transfer feature and mapping exchange fields to enhance the overall performance of the ~~modelling modeling~~ environment in terms of memory usage and computational efficiency especially for very high-resolution
high-resolution applications (< 3 km), ~~2)~~ (2) possibility of automatic detection of accelerators (GPUs) through the use of driver component and assigning available GPU resources automatically to the co-processing component for rendering, ~~3) improving~~
30 ~~modelling~~ (3) improving modeling system and co-processing component to allow nested applications (both atmosphere and ocean), ~~4)~~ (4) developing more application of the integrated modeling environment (possibly with other ocean and atmosphere components such as WRF and MITgcm) to analyze different physical processes such as air-sea interactions in upwelling regions under extreme atmospheric forcing conditions.

Code availability. The RegESM modeling system is open source and available under the MIT License, making it suitable for community usage. The license allows to modification, distribution, private and commercial uses. The source code for all versions of RegESM driver including 1.1 is distributed through the public code repository hosted by GitHub (<https://github.com/uturuncoglu/RegESM>). The user guide and detailed information about the modeling system are also distributed along with the source code using the same code repository. The RegESM source code includes the required code patches for the individual model components to use them as a component in the modeling system. On the other hand, the source code of individual model components such as the ocean, wave, and river routing components and co-processing tool (ParaView, Catalyst) used in the modeling system are distributed mainly by their home institutes and might apply different licensing types. The reader that might want to get more information about the individual model components and their license type could refer to the websites of them. The release version 1.1 is permanently archived on Zenodo and accessible under the digital object identifier doi:10.5281/zenodo.1307212. The demo configuration of the modeling system that is used in NVIDIA GPU Technology Conference (GTC) 2018 is also permanently archived on Zenodo and accessible under the digital object identifier doi:10.5281/zenodo.1474753. The repository also includes detailed information about the installation of the individual components of the modeling system, third-party libraries, and commands to create Docker container.

Competing interests. The author declare that he has no conflict of interest.

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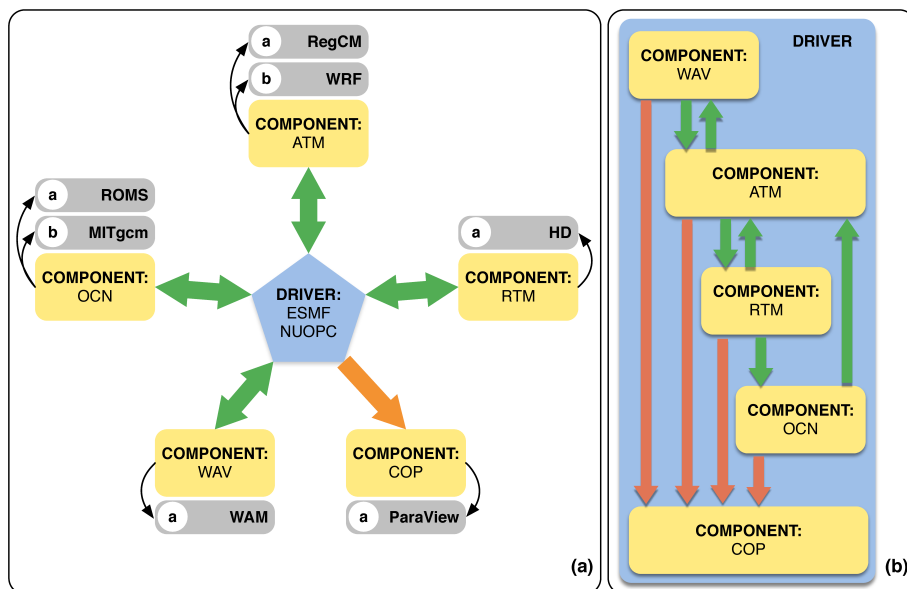


Figure 1. Design of the RegESM coupled modeling system: (a) model components including co-processing component, (b) their interactions (orange arrows represent the redistribution and green arrows shows regridding interpolation).

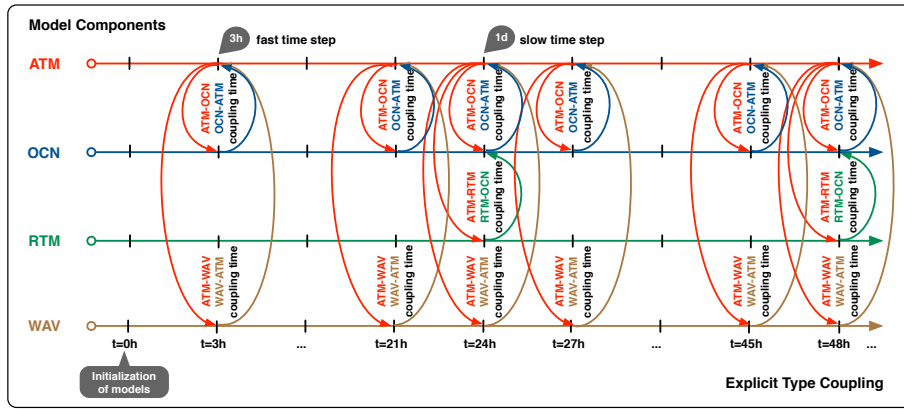


Figure 2. The run sequence of model components in case of explicit type coupling. In this case, the fast coupling time step is used for the interaction between the atmosphere, ocean and wave components. The slow coupling time step is only used to interact with the river routing component.

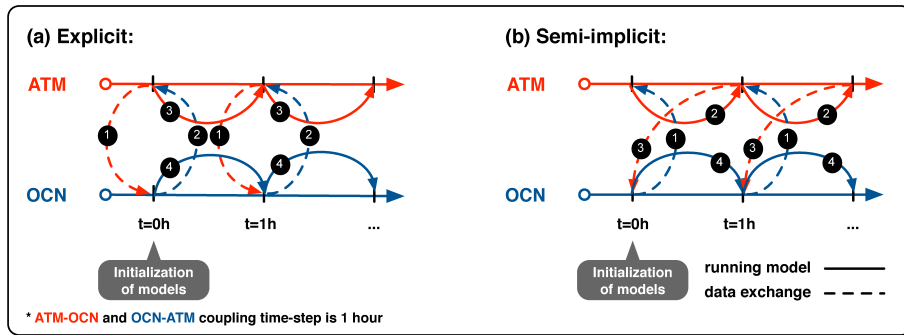


Figure 3. Schematic representation of (a) explicit and (b) semi-implicit model coupling between two model components (atmosphere and ocean). The numbers indicate the execution orders, which is initialized in each coupling interval.

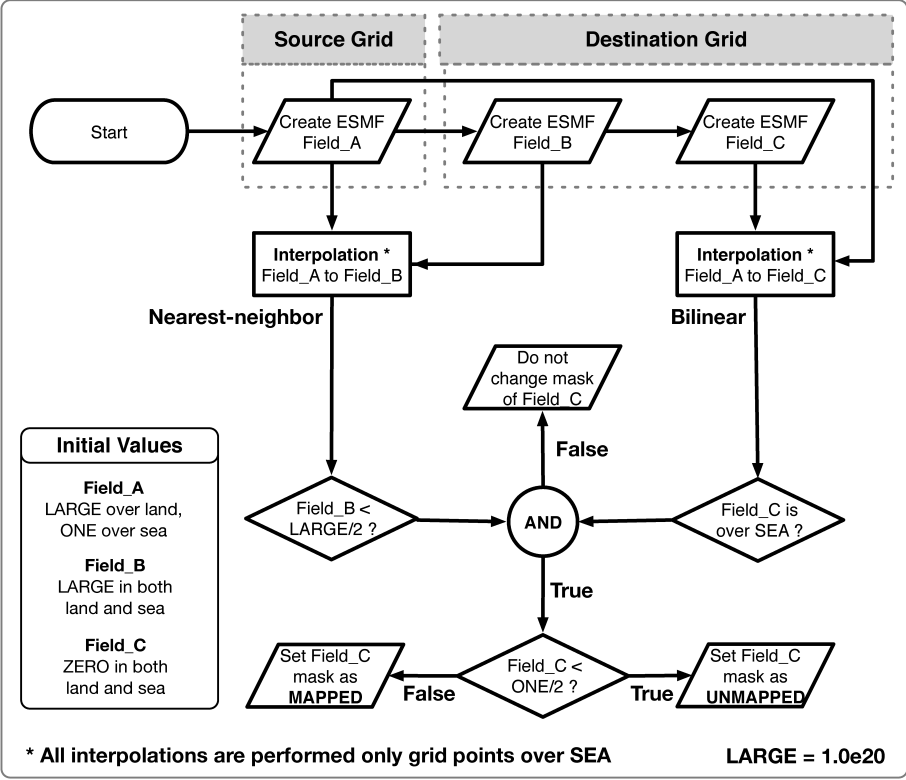


Figure 4. Processing flow chart of the algorithm to find mapped and unmapped grid points for two-step interpolation.

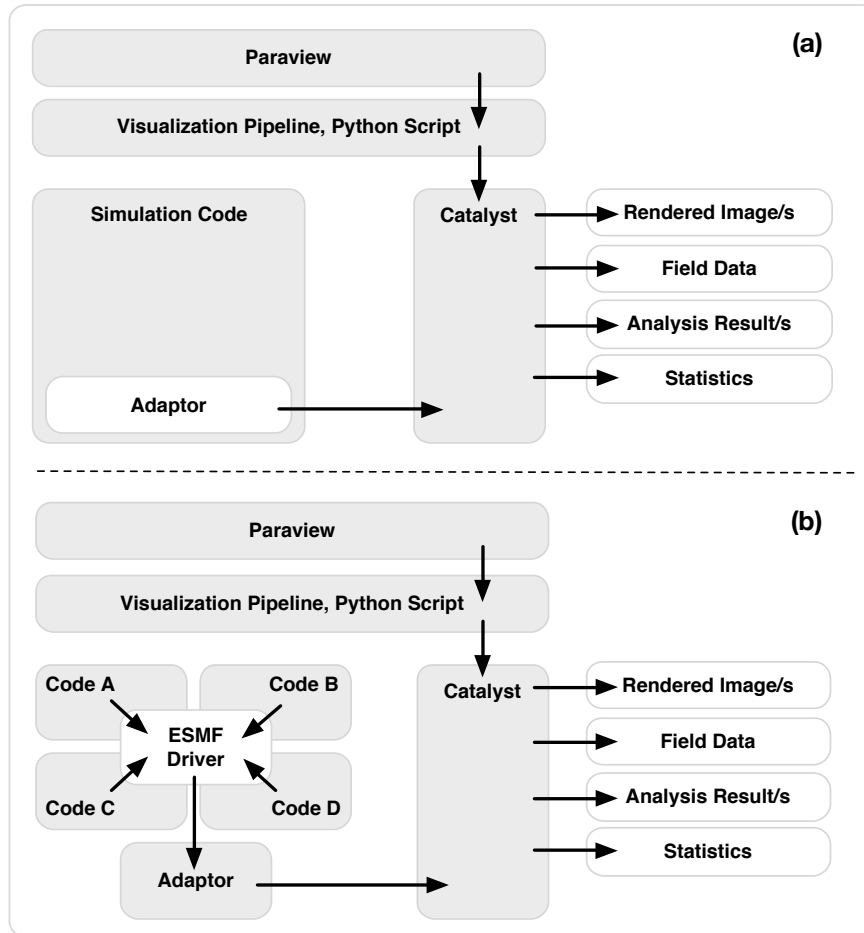


Figure 5. Comparison of the  (a) conventional and  (b) ESMF integrated in-situ visualization system.

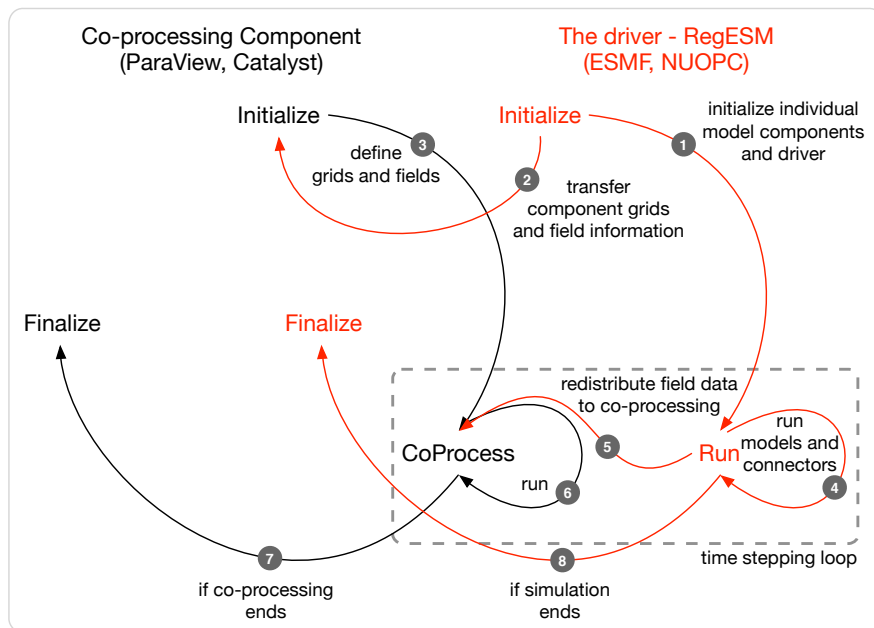


Figure 6. The interaction between driver defined by ESMF, NUOPC and co-processing component (Paraview, Catalyst).

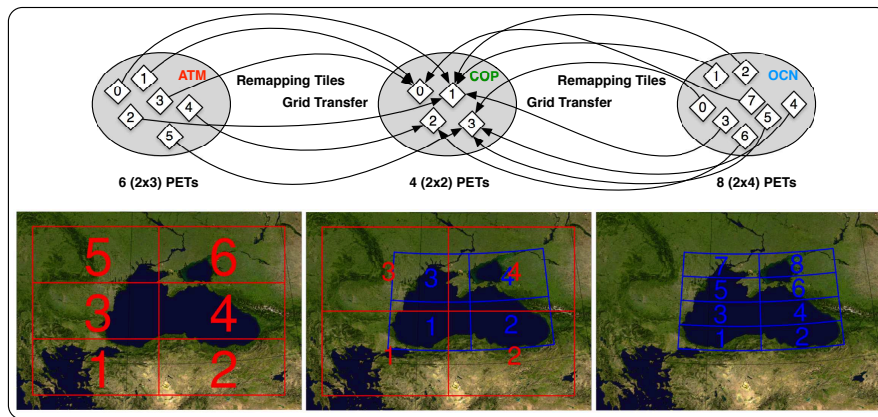


Figure 7. ~~Two-component~~ Two-component (atmosphere and ocean) representation of grid transfer and remapping feature of ESMF/NUOPC interface.

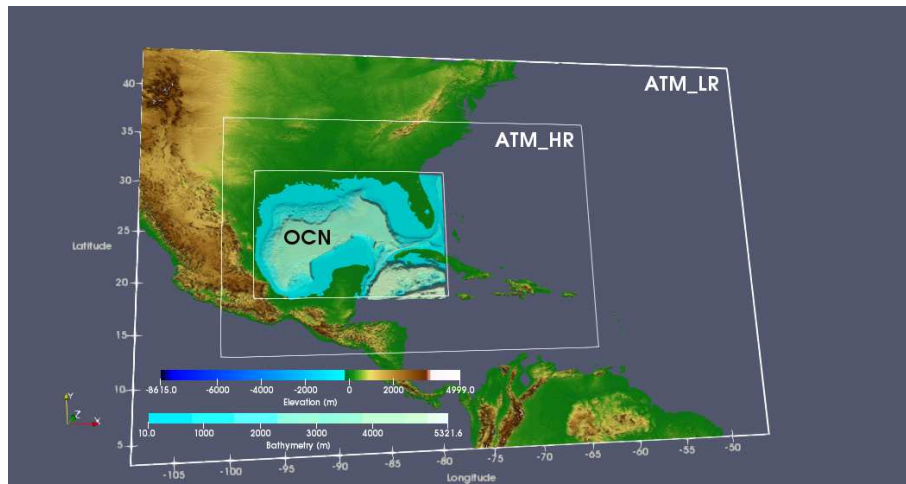
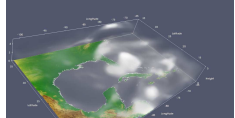
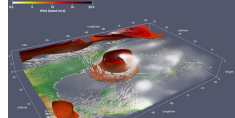
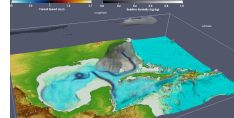
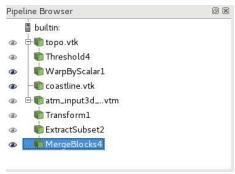
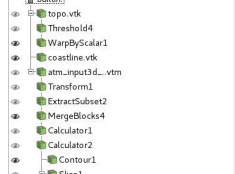
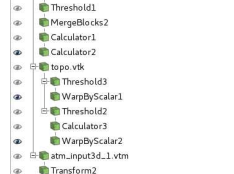


Figure 8. Domain for the RegESM simulations with topography and bathymetry of the region. The solid white boxes represent boundaries of the atmosphere (both outer and inner) and ocean model domains.

Table 1. Tested model configurations for benchmark simulations. Note that the dimension of vertical coordinates of ATM and OCN components are shown \pm here after vertical interpolation from sigma to height and s-coordinates to depth.

	P1: Case I	P2: Case II	P3: Case III
Visualization			
Pipeline			
Primitives	ATM: Contour for topography, polyline for coastline and direct volume rendering for clouds	ATM: same with previous case but it includes iso-surface for wind speed and glyph for wind at specified level	ATM: Contour for topography, iso-surface for wind speed colored by relative humidity OCN: Contour for bathymetry, direct volume rendering for current
Domain Size	ATM LR: 170 x 235 x 27 HR: 880 x 1240 x 27	ATM Same with Case I	ATM Same with Case I OCN 653 x 487 x 21
Number of Fields	1 x 3D ATM Relative Humidity	4 x 3D ATM Relative Humidity Wind (u, v, w)	4 x 3D ATM Relative Humidity Wind (u, v, w) 4 x 3D OCN Ocean Current (u, v, w) Land-Sea Mask
Data Size ATM+OCN (MB)	LR: 8.3 HR: 224.0	LR: 33.2 HR: 896.0	LR: 33.2+25.4 = 58.6 HR: 896.0+25.4 = 921.4
Time (s)	LR: 2.3 – 3.7 HR: 17.7 – 65.0	LR: 2.3 – 3.8 HR: 18.4 – 79.3	LR: 6.8 – 14.6 HR: 7.8 – 10.1

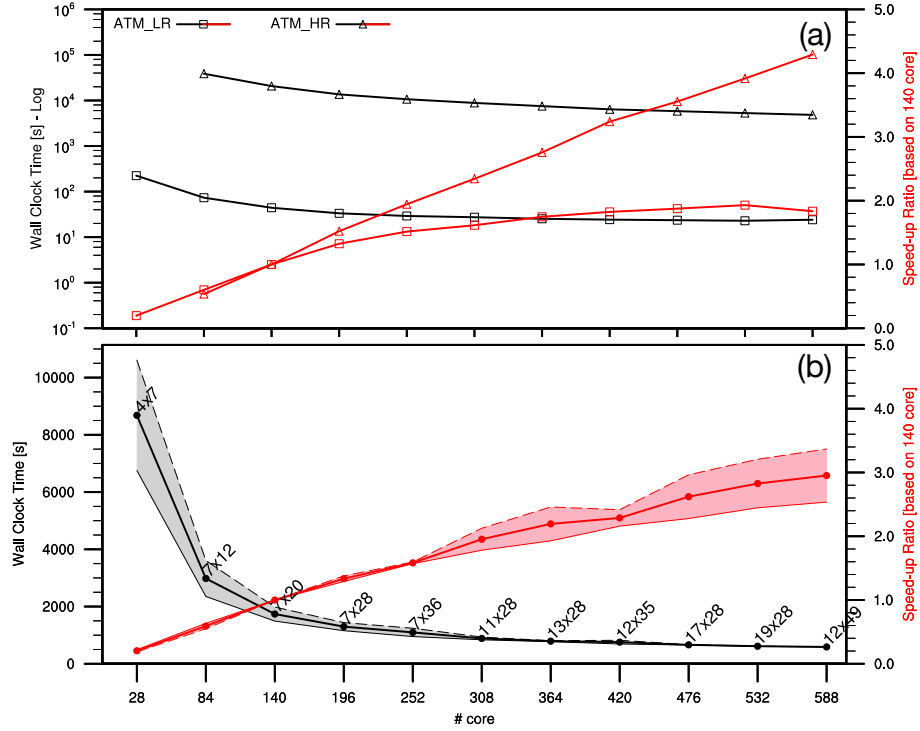


Figure 9. Benchmark results of standalone (a) atmosphere (ATM; both LR and HR) and (b) ocean (OCN) models. Note that timing results of the atmosphere model is in log axes to show both LR and HR cases in the same figure. The black lines represent measured wall clock times in second and red lines (and shaded envelope) show speed-up. The best two-dimensional decomposition parameters, timing results, and speed-up are shown as a line for the ocean model case.

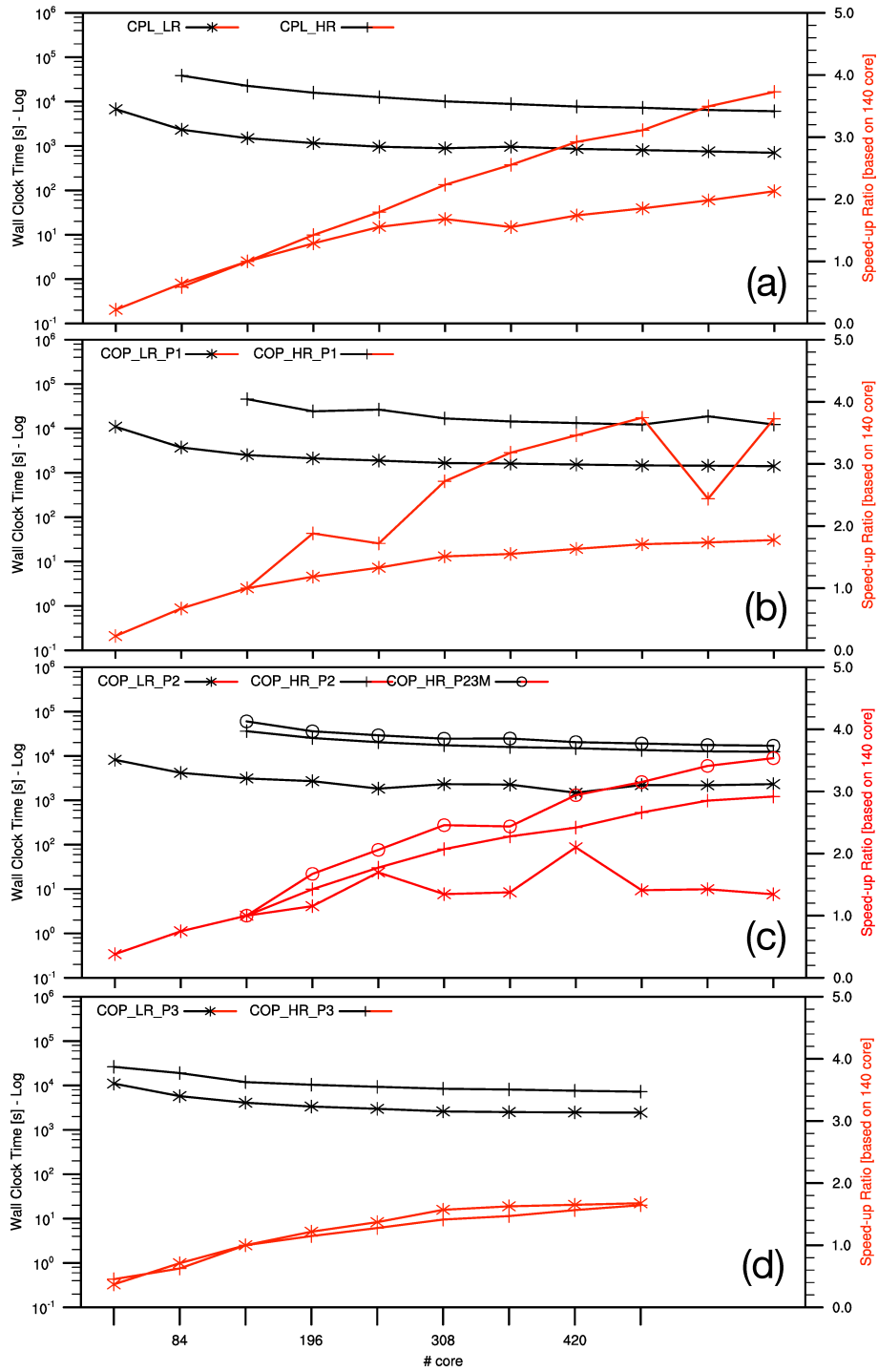


Figure 10. Benchmark results of ~~coupled model~~ (a) LR (a) CPL simulations (b) COP simulations with P1 visualization pipeline, (c) COP simulations with P2 visualization pipeline and (b) HR cases (d) COP simulations with P3 visualization pipeline. CPL represents the two-component ~~case modeling system~~ (ATM and OCN), and COP ~~shows indicates~~ three-component ~~case including modeling system~~ (ATM, OCN and co-processing ~~component~~). Note that the HR case requires at least 140 cores to run and the speed-up results are given based on 140 cores.

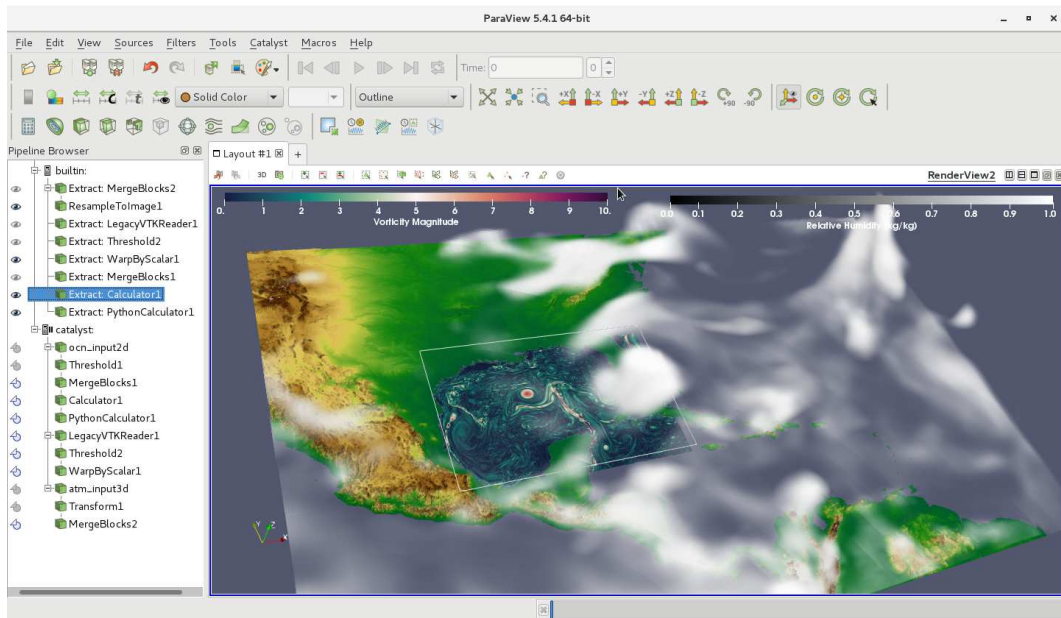


Figure 11. Volume rendering of atmospheric relative humidity field (*atm_input3d*) as well as vorticity field in the ocean surface (*ocn_input2d*) from COP_LR simulation using ParaView Catalyst in live mode.

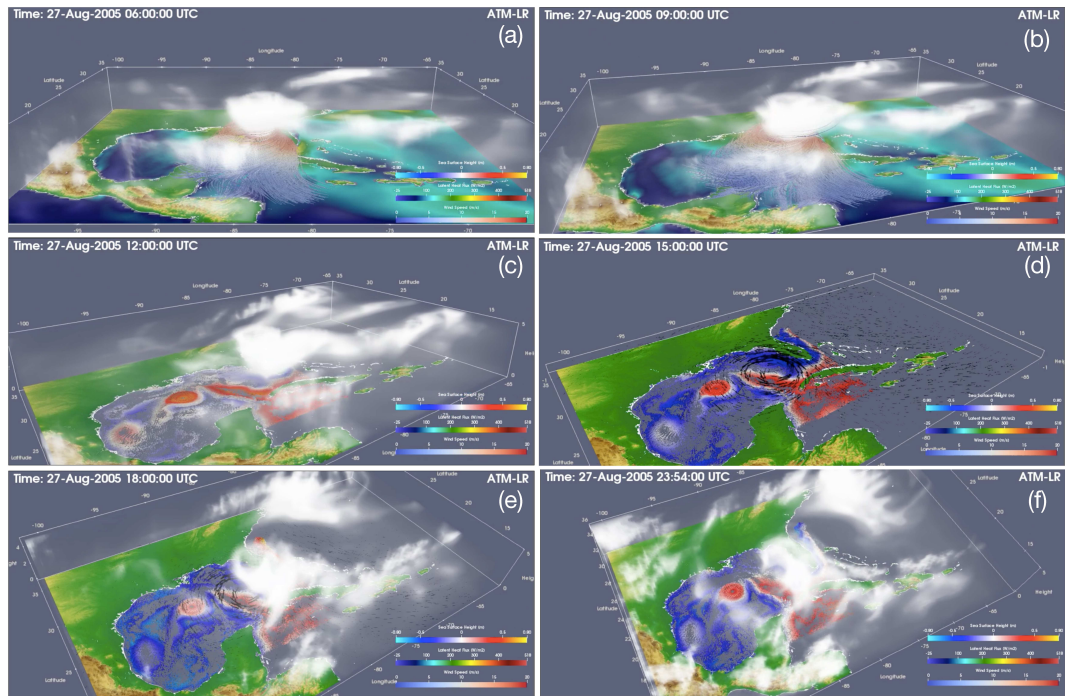


Figure 12. Rendering of multi-component (ATM-OCN-COP) fully coupled simulation using ParaView. The temporal interval for the processed data is defined as 6-minutes. ~~The evolution of the hurricane is shown in supplemental video.~~

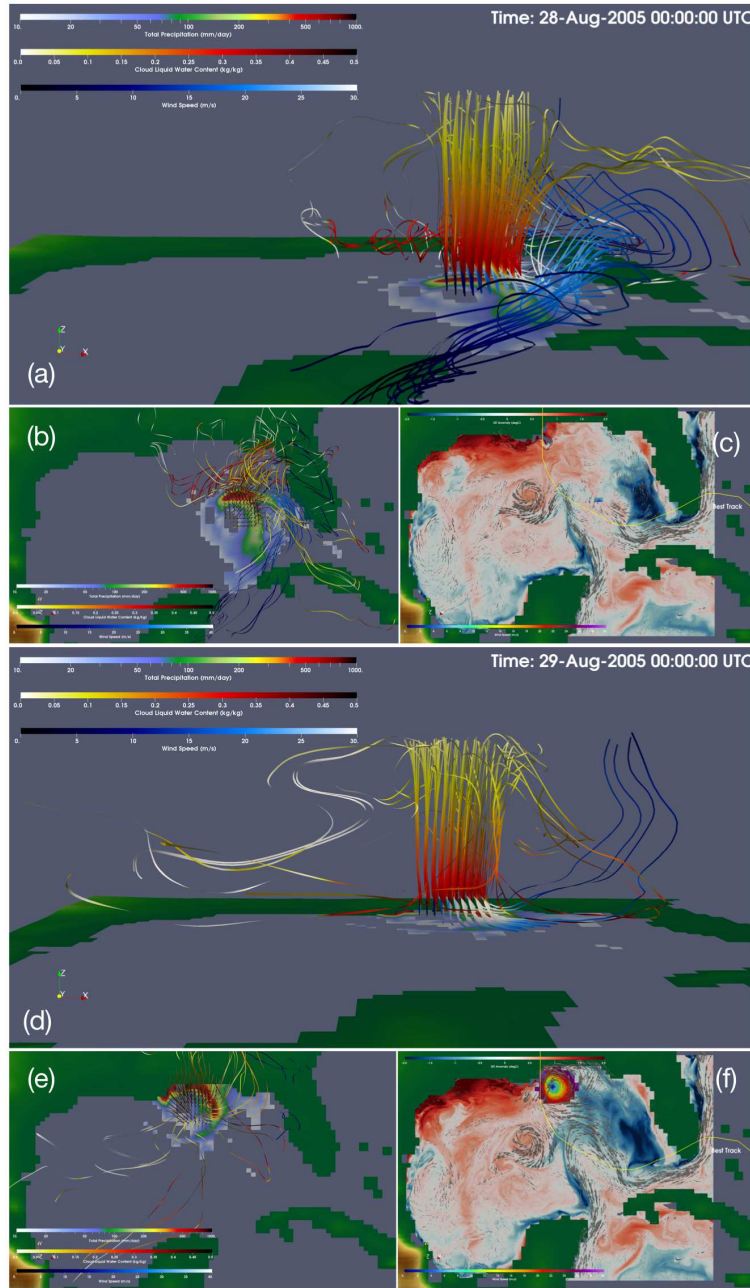


Figure 13. Rendering of three-dimensional vorticity streamlines (m/s^{-1}), total precipitation (mm/day) and sea surface temperature anomaly (degC) of COP_LR simulation for 28-Aug-2005 00:00 UTC (a-c) and 29-Aug-2005 00:00 UTC (d-f). Streamlines are calculated only from the eye of the hurricane. In this case, red and yellow colored forward streamlines represent cloud liquid water content (kg/kg), and blue colored backward streamlines indicate wind speed (m/s). The yellow solid line represents the best track of Hurricane Katrina, which is extracted from HURDAT2 database.

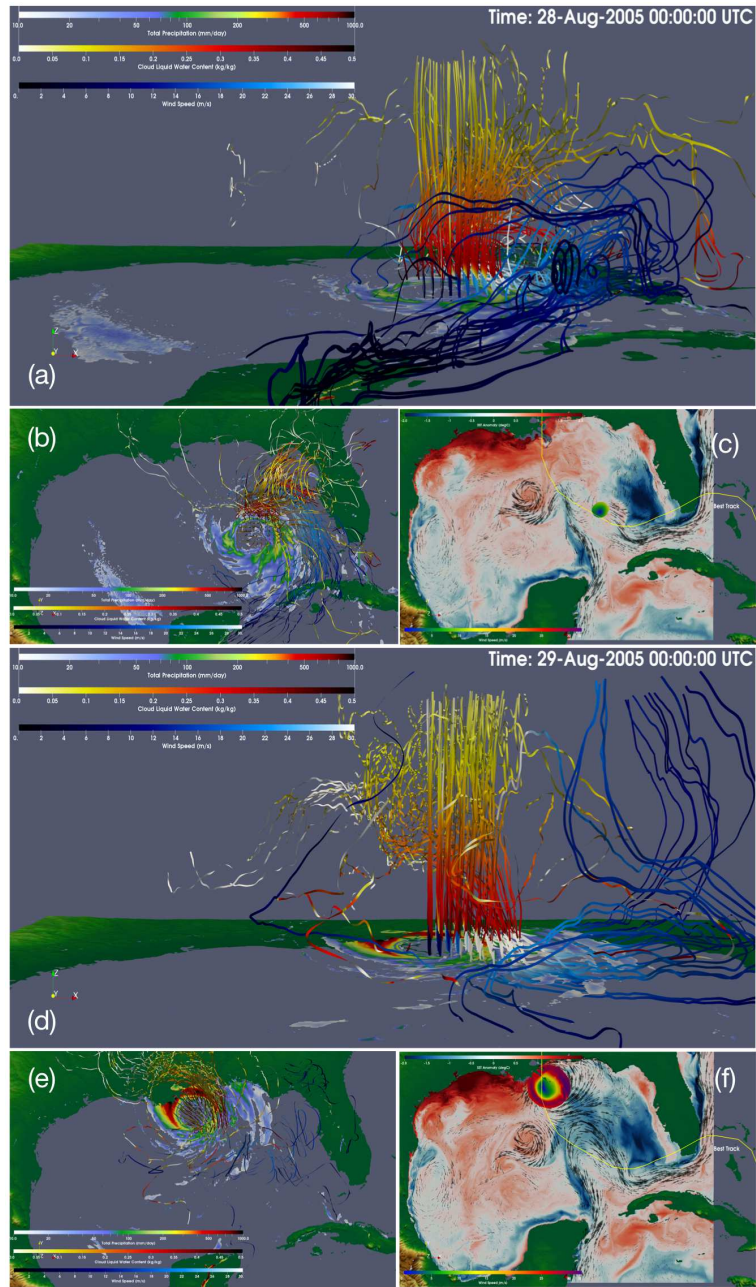


Figure 14. Same with Fig. 13 but for COP_HR simulation. The comparison of low and ~~high-resolution~~ high-resolution model results is shown in the supplemental video.