

1 **Quantifying the impact of bedrock topography**
2 **uncertainty on 100-year Pine Island Glacier projections**

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10 **Key Points:**

- 11 • Uncertainty in topography estimates has a significant impact on predictions
12 • BedMachine topography simulations within range of uncertainty, Bedmap2 more
13 stabilizing
14 • Pine Island Glacier is predicted to transition into more unstable state late mid-
15 century for strong climate forcing

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Abstract

The predicted Antarctic contribution to global-mean sea-level rise is one of the most uncertain among all major sources. Partly this is because of instability mechanisms of the ice flow over deep basins. Errors in bedrock topography can substantially impact the resilience of glaciers against such instabilities. Here we analyze the Pine Island Glacier topography to derive a statistical model representation. Our model allows for inhomogeneous and statistically dependent uncertainties and avoids unnecessary smoothing from spatial averaging or middle-of-the-road interpolation. A set of topographic fields is generated which properly represents the topographic uncertainty in our ice sheet model simulations with lower and upper end climate forcings. The bedrock uncertainty alone creates a 5% to 25% uncertainty in the predicted 100-year sea level rise contributions. Ice sheet model simulations on this new set are consistent with simulations on the frequently used BedMachine topography but diverge from Bedmap2 simulations.

Plain Language Summary

We investigate the impact of uncertainties in the elevation of the bedrock underneath the ice of a particularly vulnerable glacier in Antarctica. Our approach allows us for the first time to estimate how much future projections depend on knowledge of the bedrock elevation. A main focus of this study is to represent our current expertise of the bedrock elevation as closely as possible so that our simulations accurately reflect the extent of our knowledge of the future glacier behaviour. In summary, we find that the mass of ice lost in 100-year simulations, which contributes to the global mean sea level, can be affected by up to 25%. This highlights the value of closely-spaced bedrock measurement and of careful consideration of related uncertainties in ice-sheet simulations.

1 Introduction

The Antarctic ice sheet is one of the major sources of global sea level rise and is currently losing mass at a rate of around 0.5 to 0.6 mm global mean Sea Level Equivalent per year (mm SLE a^{-1}), predominantly in the Amundsen Sea Embayment (ASE) area of the West Antarctic Ice Sheet (WAIS) (Shepherd et al., 2018; Bamber et al., 2018). The future response of the Antarctic ice sheet to a changing climate is one of the least well understood aspects of climate predictions (Oppenheimer et al., 2019).

Changes in the Antarctic ice sheet mass balance are largely governed by changes in the Surface Mass Balance (SMB) and ocean forcing via dynamical processes such as changing buttressing from ice shelves. Ice shelves, the floating extensions of grounded ice streams, can be weakened by elevated ocean and/or atmospheric temperatures and consequently melt or collapse. Buttressing ice shelves have a stabilising effect on the ice sheet with the potential to suppress or delay Marine Ice Sheet Instability (MISI) (Schoof, 2007; Joughin & Alley, 2011). MISI can occur at ice sheets on retrograde (up-sloping in flow direction) topographies below sea level. Here a retreat of the grounding line (the transition from grounded to floating ice) will increase the ice thickness above it. For idealised conditions the mass flux across the grounding line increases rapidly with the ice thickness (Schoof, 2007). This additional mass loss can lead to an imbalance of the system causing a further retreat of the grounding line. Large areas of the WAIS, including Pine Island Glacier (PIG), one of the two major glacial systems of the ASE, lie on such retrograde slopes (Fretwell et al., 2013).

In the satellite record the ASE shows significant rates of thinning (Rignot et al., 2008; Mouginot et al., 2014; Shepherd et al., 2018), which have been linked to enhanced ocean melt from warm Circumpolar Deep Water entering the continental

shelf (Dutrieux et al., 2014; Naughten et al., 2018; Rignot et al., 2014). This might have triggered Marine Ice Sheet Instability in the ASE at present (Joughin et al., 2014; Favier et al., 2014; Alley et al., 2015). Bamber and Dawson (2020) find a recent reduction of rates of mass loss from PIG even though it has maintained a negative mass balance and elevated flow speeds. This behaviour could be related to lower ocean temperatures in 2012-2013 compared with the 2000s (Milillo et al., 2017). In summary, PIG currently loses mass, shows strong sensitivity to ocean-induced melt and is situated on a bedrock topography which makes it more vulnerable.

Predictions of the dynamic ice sheet response are challenging because of poorly observed local physical properties of the ice and the bedrock underneath. One of these factors concerns the bedrock elevation maps which suffer from errors from the instruments and gaps in the record. The lack of local measurements creates a need for spatial interpolation which adds additional uncertainties. It is worth highlighting that MISI depends on the topography gradient local to the grounding line. Topography measurement errors and interpolation are likely to have a stronger relative impact on gradients than on the absolute elevation.

Here we generate statistically a set of bedrock topographies which represent the range of uncertainties from topographic observations and interpolation. These topographies are therefore in agreement with observational constraints while aiming to fully represent their uncertainties. We then assess the impact of topographic uncertainties by using the set of bedrock topographies in an ensemble of ice sheet model simulations. We use the BISICLES ice sheet model to simulate PIG changes this century under two climate forcings – low, and strongly increasing - using three different friction laws. Thereby we show how bedrock uncertainty translates into predictive uncertainty for a large range of plausible future scenarios, friction laws and topographies.

In Section 2 we will introduce the airborne radar measurements used here and analyse the geostatistical properties. Based on this we set up simulations of the ice sheet model BISICLES in Section 3, starting with the generation of topographies, initialisation and inversion of model parameters, followed by a description of the forcing we use for 100-year simulations. Simulation results are presented in Section 4 with focus on the contribution to uncertainty in sea level, and are discussed in Section 5.

2 Data and Methods

We summarize our knowledge of the real bedrock in a multivariate random variable which is approximated by a Gaussian Process (GP). By using this statistical model, we can represent uncertainties in elevation observations considered as random variables, by sampling spatial fields of bedrock topography within the range of local uncertainties and spatial covariance structure. To define a GP model we need training data and covariance function parameters. Ungridded airborne radar measurements are analysed to estimate the statistical characteristics of the bedrock topography and measurement uncertainties. This provides us with the required GP model covariance function parameters. We train the GP to match observed values, given the observational uncertainty. From this GP model we draw random samples to represent the topography and its uncertainty in the ice sheet model BISICLES.

The airborne Radar Echo Sounding (RES) dataset used here is compiled from two different sources, namely the one described in Holt et al. (2006), and Operation Ice Bridge IRMCR2 Level-2 data from October 2009 to December 2017 (Paden et al., 2010, NSIDC, last accessed in September 2019 through <https://cmr.earthdata.nasa.gov>). These radar measurements do not measure bedrock topography underneath ice shelves. The PIG catchment area is defined as in Mouginot et al. (2017) based on Rignot et al. (2013). About 1.5% of the 2.3 million measurements in this basin are removed here due

115 to inconsistencies. For training, the RES dataset has to be sub-sampled to reduce its
 116 size, due to computational constraints. This is done by imposing a 2 km \times 2 km grid
 117 onto the region and randomly selecting one measurement from each box if available
 118 (about 25 000 measurements). This is done to ensure a good spatial coverage while
 119 avoiding smoothing effects from averaging. The covariance function is derived from
 120 semivariograms on fully random (no use of boxes) subsets of 100 000 measurements.
 121 Exponential functions are fitted to the semi-variance on scales of 25 km to 50 km to
 122 derive the nugget, length scale and far-field variance to describe the spatial correlation
 123 characteristics. These exponential fits capture the semivariance very well (Wernecke,
 124 2020, section 5.1.2) which motivates our use of an exponential covariance function for
 125 the GP.

The exponential covariance function, c_E , is defined as:

$$COV(x_1, x_2) = c_E(r, \sigma_c^2, \ell) = \sigma_c^2 \exp\left(-\frac{r}{2\ell}\right), \quad (1)$$

126 where $COV(x_1, x_2)$ is the covariance in the bedrock topography at the locations x_1 and
 127 x_2 , σ_c^2 is the far-field variance (or sill), r is the physical distance between the locations
 128 x_1 and x_2 and ℓ is the characteristic correlation length scale. The randomized sub-
 129 sampling for deriving the covariance parameters and the training data is repeated to
 130 capture the impact on the final simulations. See Wernecke (2020) Section 5.1.2 for
 131 more information.

132 We generate random two-dimensional sample fields within the range of the local
 133 measurement uncertainties which also adhere to the full spatial covariance matrix
 134 and with it the uncertainty estimate, as illustrated in Figure 1a. The topographic
 135 uncertainty is clearly increasing with distance to the closest measurement (flight line)
 136 and is often above 50 m (one standard deviation), even in regions with close sampling.

137 The computational demand of sampling from a GP scales with the number of
 138 spawned grid cells n by $\mathcal{O}(n^3)$, which imposes a limit on this number. We use the
 139 python GPy module to draw 12 samples on a 4 km \times 4 km grid in the PIG catchment
 140 area. We use Bedmap2 geometry (bedrock topography and ice thickness), brought to
 141 the same resolution by averaging, for the remainder of the rectangular model domain
 142 and ungrounded area. The ice surface elevation is considered well known and the ice
 143 thickness is adjusted for all statistically generated topographies to match the Bedmap2
 144 surface elevations. The resulting 12 topographies are accompanied by two reference
 145 topographies, Bedmap2 (Fretwell et al., 2013) and BedMachine (Morlighem, 2019;
 146 Morlighem et al., 2020), with the same resolution.

147 3 Simulations

148 We use all combinations of the 14 topographies described above with three fric-
 149 tion laws and two climate forcings, resulting in a total of 84 simulations. The simula-
 150 tions are performed by the adaptive mesh ice sheet model BISICLES (Cornford et al.,
 151 2013, 2015), which is a finite-volume model with vertically integrated stress approxima-
 152 tions (Wernecke, 2020, sections 2.1 and 5.2.2 for more information). Each topography
 153 is used separately to find basal traction coefficient and effective viscosity fields for PIG
 154 using the BISICLES inverse model framework with a compilation of satellite based
 155 ice surface velocities from Rignot et al. (2017, 2011). Figure 1b illustrates the initial
 156 velocity field of the main PIG trunk.

157 The Weertman friction law is :

$$\tau_b = C_m \cdot |u_b|^{m-1} \cdot u_b$$

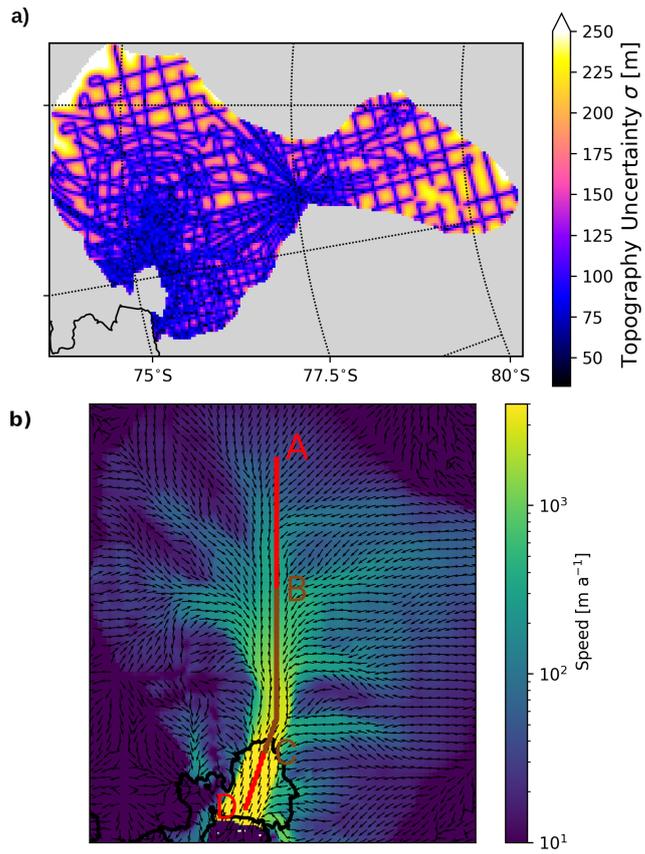


Figure 1. a: One standard deviation of trained GP which increases with distance from measurements (flight lines) and b: Initial PIG ice velocity direction (arrows) and speed (colours), for the main trunk (left half of panel a) of PIG flow including the approximate central flow line (red and brown).

with τ_b being the basal stress tangential to the base of the ice, C_m is the spatially varying basal traction coefficient for a given friction law exponent m and u_b is the basal ice velocity. We use $m = 1$ for linear friction, $m = 1/3$ for nonlinear friction and $m = 1/8$ for strongly nonlinear friction (called plastic friction in the following). Ice flow outside of the PIG catchment area is suppressed for numerical stability.

3.1 Climate forcing

For the model simulations we use two different climate forcings with changing ocean melt and SMB. These two forcings are intended to encompass the range of likely climate scenarios:

- The **low forcing** uses an RCP2.6 SMB and constant-in-time ocean melt rates.
- The **high forcing** uses an RCP8.5 SMB and linearly increasing ocean melt, starting at the low forcing rates at the beginning and adding 200 % by the end of the 100-year model simulations

As SMB we use data from NorESM1-M, a CMIP5 atmosphere-ocean coupled global climate model (Bentsen et al., 2013). Of the three models selected in Barthel et al. (2020) for the ice sheet model intercomparison project ISMIP6 (Seroussi et al., 2020) for consistency with the CMIP5 multi-model ensemble, NorESM1-M has the highest rank in the CMIP5 cross-model performance analysis by Agosta et al. (2015). The simulations show below median atmospheric warming and relatively strong 21st century ocean warming compared with the multi-model ensemble (Barthel et al., 2020).

The ocean melt at the beginning of the simulations is based on temperature and salinity profiles corresponding to the Warm₀ setup in Favier et al. (2019) which is based on oceanographic measurements from Dutrieux et al. (2014). The profiles have warm and salty water at depth and colder, fresher water towards the surface. This structure is caused by the overturning circulation of warm Circumpolar Deep Water which mixes with glacial meltwater before being transported offshore near the surface. We use a local squared ocean melt forcing parameterisation since it is the best local parameterisation in Favier et al. (2019). The resulting total PIG initial melt rate of 84.6 Gt a⁻¹ (using Bedmap2 geometry) is in good agreement with other estimates (Jourdain et al., 2020; Dutrieux et al., 2014; Rignot et al., 2013).

Predictions of future ocean melt forcing are highly uncertain, but cannot be ignored for 100-year model simulations. The two forcings used here are designed to represent reasonable low and high melt scenarios without being bound to specific climate projections. Naughten et al. (2018) use the Southern Ocean quality of 19 CMIP5 models to select a forcings for the regional ocean model FESOM. The ocean model predicts a year 2100 ASE ocean melt increase of about 200% (multi-model mean) to 300% (ACCESS-1.0) for RCP8.5. However, Naughten et al. (2018) note a cold bias of about 2 K in the bottom water temperature on the Amundsen Sea continental shelf at the beginning of the simulations. They argue that the warming should be seen largely as reversal of a model bias which makes it very likely that the increase in melt is overestimated. This overestimation might be up to about 150% in melt increase (Wernecke, 2020, Section 5.2.3). We select an increase of 200% in 100 years as a best guess upper-end melt representation.

We cannot rule out that current ocean conditions are a positive anomaly caused by internal variability. Climate projections of ice shelf ocean melt rates for the ASE often show positive trends (Naughten et al., 2018; Alevropoulos-Borrill et al., 2020; Jourdain et al., 2020), but some projections show temporarily negative ocean temperature anomalies compared to the early 2000s (Jourdain et al., 2020; Alevropoulos-Borrill

206 et al., 2020). We apply a constant ocean melt forcing, consistent with recent past rates,
 207 as reasonable lower-end forcing.

208 4 Results

209 4.1 Simulations

210 In the first years we see high-amplitude small spatial-scale rates of ice thickness
 211 change which diminish over time (Wernecke, 2020, Section 5.3.2). This is an adjust-
 212 ment of the model to a self-consistent state. In retrospect we should have implemented
 213 a spin-up period in the simulations with a constant forcing before the forced projec-
 214 tions start. Instead our simulations start with forcing, including SMB corresponding
 215 to year 2000 AD (used as start year). By careful inspection (Wernecke, 2020, Section
 216 5.3.2) we define the 15th year as reference which is used as baseline for the following
 217 calculations. In this way the impact of initial adjustments on the results is minimized.

218 While the statistically generated topographies agree well with the reference to-
 219 pographies (in particular BedMachine) on average, the samples used for simulations
 220 (e.g. Figure 2, right) show stronger regional variability. The scale of this variability
 221 is in agreement with very high-resolution observations (Bingham et al., 2017; Wer-
 222 necke, 2020, Section 5.3.1). For GP samples topography uncertainties are represented
 223 within the sample while Bedmap2 and BedMachine use averaging and interpolation
 224 techniques which create smoother fields (with spatially localised uncertainties).

225 The ice geometry and flow speed along the downstream sector of the central
 226 PIG flow line (from location B to D in Figure 1b) is illustrated for plastic friction
 227 and Bedmap2 as well as BedMachine in Figure 2, left. For low forcing the glacier
 228 thins slightly without the grounding line retreating much. At the same time the ice
 229 speed reduces, in particular in the fast-flowing ice shelf. Note that PIG is currently
 230 out-of-balance so that a (stabilizing) slow-down is not contradicting further mass loss.
 231 A partial slow-down of the PIG ice velocities is also predicted for the flow line model
 232 simulations in Gladstone et al. (2012) and is found in the optimized (central) simu-
 233 lations from Nias et al. (2016) for all combinations of bedrock and friction law (not
 234 shown).

235 For the high forcing scenario we see very different pictures for BedMachine and
 236 Bedmap2 geometries: For BedMachine the ice near the grounding line accelerates over
 237 the 85 year projection period from less than 4000 m a^{-1} to more than 5000 m a^{-1} . The
 238 speed-up extends more than 150 km upstream (red lines in Figure 2). For Bedmap2
 239 the high forcing scenario does not show noteworthy acceleration or thinning.

240 The flow line characteristics of two topographies generated here are shown on the
 241 right of Figure 2. Simulations with statistically generated topographies share the same
 242 features of those using BedMachine: little changes to the ice geometry with some slow-
 243 down for low forcing, and pronounced thinning with significant grounding line retreat
 244 and accelerating ice for high forcing.

245 4.2 Sea level rise contribution

246 The ensemble behaviour can be categorized into two states, a steadily evolving
 247 state with approximately constant rates of mass loss (about $0.1 \text{ mm SLE a}^{-1}$) and an
 248 unstable state with mass losses up to six times faster (Figure 3, top). The timing of an
 249 ensemble member to become unstable depends strongly on the topography and forcing:
 250 most high melt simulation become unstable between 2055 and 2075. This timing seems
 251 not to depend on the friction law (Figure 3, top right). Low melt ensemble members
 252 remain in the steadily evolving state without exception.

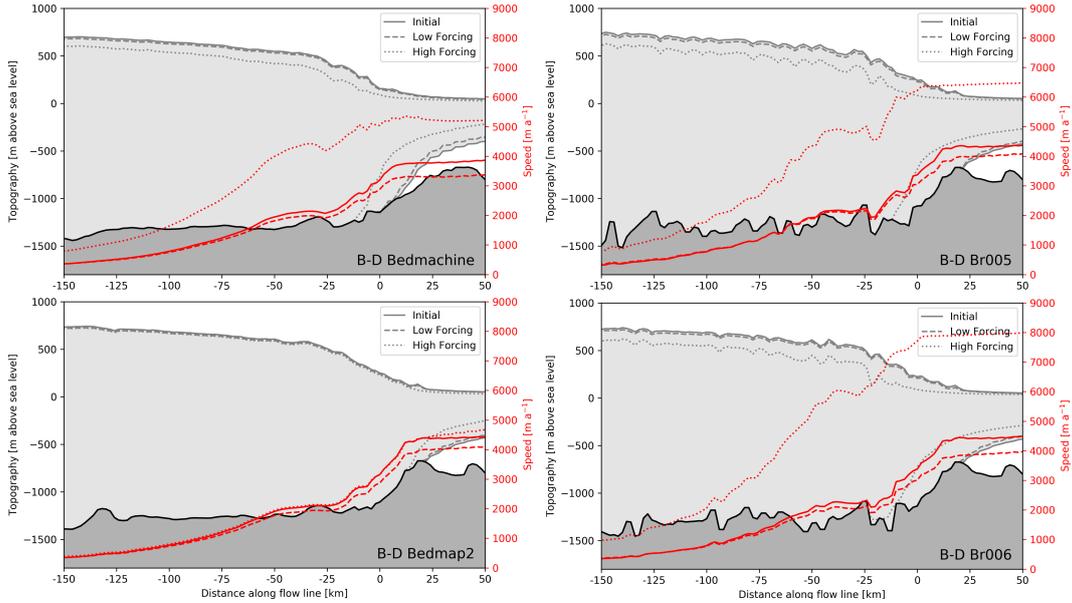


Figure 2. Profiles along PIG flow line from location B to D in Figure 1 with BedMachine (top left) and Bedmap2 (bottom left) and two statistically generated topographies (right). Shown are the bedrock underneath the ice (black), surface and basal ice boundaries (grey) and the ice speed (red) after 15 years of simulation (used as baseline; solid lines) and at the end of the 100-year simulations with high (dotted) and low (dashed) forcing, all using a plastic friction law.

Table 1. Mean 2100 sea level contribution estimates (relative to 2015) with one standard deviation of the statistically generated bedrock ensemble (both in mm SLE)

Friction law:	Linear	Nonlinear	Plastic
High Forcing:	11.3 ±2.08	15.5 ±3.86	19.4 ±5.15
Low Forcing:	6.7 ±0.31	5.6 ±0.62	4.7 ±0.87

253 The main effect of the friction law is an increase in the rate of mass loss in the
 254 unstable state with faster rates for more non-linear friction laws (Figure 3, middle).
 255 For low forcing the relationship is reversed, more linear friction leads to larger sea
 256 level contributions. This can be traced back to the slow down of the ice velocities as
 257 shown in Figure 2. Highly nonlinear friction laws facilitate decelerating ice to slow
 258 down even more and accelerating ice to speed up more than linear counterparts. This
 259 also explains why the predictive uncertainty due to the bedrock uncertainty strongly
 260 increases with non-linearity of the friction law and with stronger forcing. The standard
 261 deviation of the net sea level contribution over the 85-years ranges from 0.31 mm SLE
 262 for low forcing and linear friction to 5.15 mm SLE for high forcing and plastic friction
 263 which corresponds to about 5% to 25% of total sea level contribution (Figure 3 middle
 264 and Table 1).

265 BedMachine based simulations agree with simulations based on topographies
 266 generated here regarding the total sea level contribution. In contrast, Bedmap2 runs
 267 with high forcing are not consistent with the behaviour for all other topographies
 268 used. Instead Bedmap2 sea level rise contributions remain in the more stable, steadily
 269 evolving state regardless of forcing (Figure 3 bottom). This suggests that Bedmap2
 270 has an overly stabilising effect on PIG, even for strong melt forcing and plastic friction.

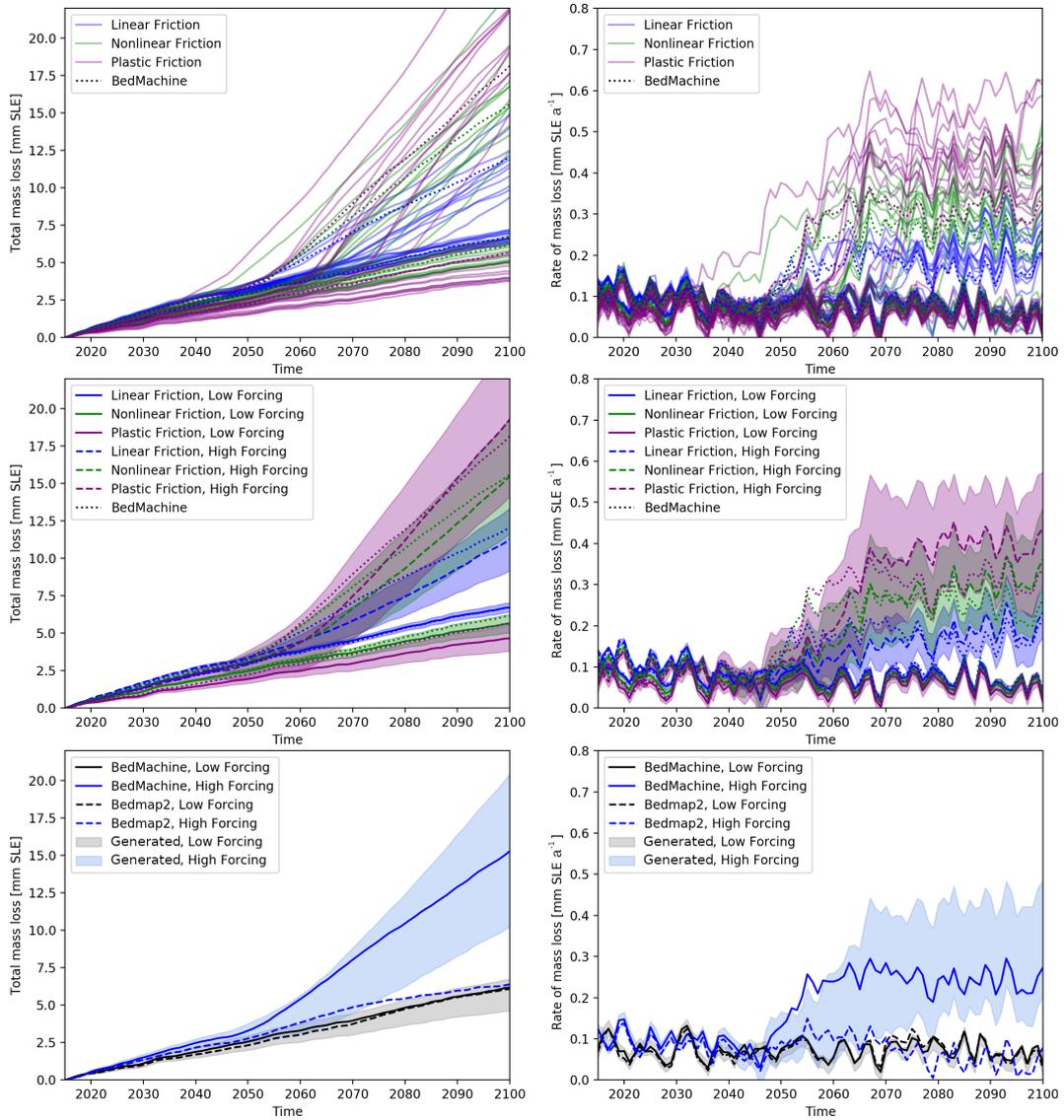


Figure 3. Net sea level contribution (left) and yearly rate (right). Individual simulations (top), grouped by friction law and forcing (middle) and grouped only by forcing including Bedmap2 (bottom). Shades correspond to \pm one standard deviation.

5 Discussion

Present-day bedrock topography uncertainty has been shown to have a strong influence on ice sheet simulations in the mid-Pliocene where the sea level contribution in 3000-year simulations varies between 12.6 and 17.9 m SLE for different noise realisations (Gasson et al., 2015). The sensitivity of BISICLES to roughness in the topography has been investigated by Sun et al. (2014) by adding noise of different spatial scales to a reference topography. The strongest impact is found for the largest scale (50 km) which, just as for our high forcing scenario, determines the timing of the system to transition into a more unstable state. In contrast to such sensitivity studies, our sample is representative of our knowledge about the topography, including likely correlation length scales and an increase in topography uncertainty with distance to measurements.

Simulations based on Bedmap2 for PIG show less sensitivity to strong climate forcing than the statistically generated topographies and BedMachine. Since our topographies agree qualitatively with BedMachine it is unclear what aspect causes the difference: BedMachine uses a mass conservation approach where topographies are relaxed to avoid large mass flux divergence (positive or negative) from unreasonable ice geometry-velocity combinations. Our topographies and Bedmap2 do not include such considerations but share a sill near the grounding line. Our topographies show at the same time considerably more variability than the relatively smooth Bedmap2 and BedMachine. We do note, however, that the Bedmap2 topography lies largely above the others within the first approximately 150 km upstream from the grounding line and that, for the same surface elevation of the ice, an elevated topography is further from hydrostatic equilibrium and could hence be less prone to retreat. Whatever the reason, the striking underestimation of mass loss for Bedmap2 simulations and high forcing relative to the other topographies (Figure 3, bottom), calls for caution in interpreting modelling results obtained with this topography.

The simulations used here have no representation of Marine Ice Cliff Instability which cannot be ruled out on these timescales. It seems, however, not possible at the moment to represent it in a well constrained way, or to predict how strong its impact could be on simulations up to year 2100.

Another clear limitation of our simulations is the resolution of statistically generated topographies of $4 \text{ km} \times 4 \text{ km}$ (which is interpolated up to 500 m within the adaptive grid refinement of BISICLES). The reason for this is not so much the Gaussian Process approach itself but the relatively high computational demand of a Cholesky decomposition which is used to generate random samples from a large covariance matrix. Evaluations of the mean field ('best estimate') would have been possible on fine resolutions, but would not have covered all of the uncertainties. It is challenging to quantify the impact of the bedrock resolution, but it should be noted that the statistically generated topographies contain much more variability than both reference topographies, and that finer resolutions would, if anything, amplify this property. Simulations using Bedmap2 topography at 1 km resolution behave very similarly to those with degraded 4 km resolution (not shown).

To represent bedrock uncertainty in future simulations it would be desirable to have reference realizations, like the set of topographies we generated here but for more general setups (ideally continent wide). This would allow different modelling groups to represent topographic uncertainty in predictions while retaining comparability (since the same samples are used). Similar approaches could be used to assess the value of additional measurements, e.g. for planning future campaigns.

In conclusion, we have been able to couple the representation of the bedrock uncertainty more closely to observational constraints in combination with the use of

322 realistic climate forcings. In particular we have shown how the uncertainty from to-
 323 pography interacts with other model parameters. This uncertainty increases with non-
 324 linearity of the friction law and with stronger (melt) forcing. One standard deviation
 325 can make up between 5% and about 25% (=5 mm SLE) of the 85-year signal, solely
 326 due to uncertainties in topography measurements and interpolation. These predictive
 327 uncertainties have been known to exist but until now remained largely omitted and
 328 unquantified. The low forcing scenario, which is more likely to be realized in very low
 329 greenhouse gas emission scenarios, would limit the PIG contribution to global mean
 330 sea level in this century. In addition we find the use of Bedmap2 to be likely to lead
 331 to an underestimation of the dynamic response of PIG and recommend the use of
 332 BedMachine if a reference topography has to be used.

333 6 Open Research

334 The simulations and bedrock topographies are publicly accessible at <https://doi.org/10.5281/zenodo.5553288>,
 335 <https://doi.org/10.5281/zenodo.5553311> and <https://doi.org/10.5281/zenodo.5553320>
 336 (linear, nonlinear and plastic friction, respectively).

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