The ULR-repro3 GPS data reanalysis and its estimates of vertical land motion at tide gauges for sea level science

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Abstract

A new reanalysis of GNSS data at or near tide gauges worldwide was produced by the university of La Rochelle (ULR) group within the 3rd International GNSS Service (IGS) reprocessing campaign (repro3). The new solution, called ULR-repro3, complies with the IGS standards adopted for repro3, implementing advances in data modelling and corrections since the previous reanalysis campaign, and extending the average record length by about 7 years. The results presented here focus on the main products of interest for sea level science, that is, the station position time series and associated velocities on the vertical component at tide gauges. These products are useful to estimate accurate vertical land motion at the coast and supplement data from satellite altimetry or tide gauges for an improved understanding of sea level changes and their impacts along coastal areas. To provide realistic velocity uncertainty estimates, the noise content in the position time series was investigated considering the impact of non-tidal atmospheric loading. Overall, the ULR-repro3 position time series show reduced white noise and power-law amplitudes and station velocity uncertainties compared to the previous reanalysis. The products are available via SONEL (https://doi.org/10.26166/sonel_ulr7a; Gravelle et al., 2022).
1 Introduction

Vertical land motion plays a crucial role in understanding sea level changes and its spatial variability (Wöppelmann & Marcos, 2016; Frederikse et al., 2020; Hamlington et al., 2020; for recent reviews and references therein). This is especially true along the coasts, where its monitoring is often an essential requirement to assess the extent of the environmental and socio-economic threats posed by changing sea levels in a warming climate at regional or local scales (Magnan et al., 2020). Changes in sea level can be measured relative to the land by tide gauges, or relative to the Earth’s center of mass by satellite altimeters (e.g., Marcos et al., 2019). In both relative (tide gauge) and geocentric (satellite) measuring systems, accurate estimates of vertical land motion are essential, either to disentangle the solid Earth contribution from other factors in tide gauge records (Woodworth et al., 2019), or to supplement satellite altimetry data to assess relative sea level change for coastal studies and planning (Poitevin et al., 2019).

In the last decades, significant efforts have been undertaken to produce accurate estimates of vertical land motion at tide gauges using Global Navigation Satellite System (GNSS) data (e.g., Sanli and Blewitt, 2001; Wöppelmann et al., 2007; Hammond et al., 2021). Wöppelmann et al. (2007) showed the importance of applying a homogeneous GNSS data reanalysis strategy across the entire data span; that is, using the same modelling, corrections and parameterization, to address the demand of accurate position time series and velocities for sea level studies. This conclusion was reached independently by Steigenberger et al. (2006) within the International GNSS Service (IGS; Johnston et al., 2017). Since then, the IGS has conducted several data reanalysis campaigns, stimulated by progress in modelling and corrections, lengthening of measurement records and updates of the International Terrestrial Reference Frame (ITRF) realizations (Rebischung et al., 2016).

In 2019, the IGS launched a third reprocessing campaign, designated as ‘repro3’, involving the international GNSS community (Rebischung, 2021). The University of La Rochelle (ULR) group contributed to this effort with a solution (ULR-repro3), that specifically includes a large selection of reliable GNSS stations near tide gauges. This paper describes the latest ULR solution in a series, complying with the modelling and corrections adopted for ‘repro3’ (Rebischung, 2021; http://acc.igs.org/repro3/repro3.html), which succeeds previous releases (Wöppelmann et al., 2009; Santamaria-Gomez et al., 2017). It specifically highlights the time series of station positions and their vertical velocities, which are the main products of interest.
for the sea level community. A crucial piece of information for the practical use of these products is their uncertainties, which must account for the presence of time-correlated stochastic variations (or noise) in the position time series (Williams et al., 2004). Consequently, this paper also presents the statistical modelling strategies employed to derive realistic uncertainty estimates. These results are presented together with a comparison with respect to the previous ULR solution to appraise the progress accomplished over the past seven years.

2 The ULR-repro3 products

2.1 Input data

Although the term GNSS is employed throughout the manuscript, the ULR-repro3 reanalysis considered Global Positioning System (GPS) observations only. The GNSS measurements were retrieved from the SONEL archive (www.sonel.org) in the form of station-specific daily files in the international standard RINEX format. These contain dual-frequency carrier phase and pseudo-range measurements with a typical sampling of 30s. SONEL holdings include data from over 1,200 stations around the world, amounting to over 6,300,000 daily files. A station selection was applied with the criteria of targeting time series with over three years of continuous GNSS measurements and 70% completeness, located at or near a tide gauge. The term “continuous” denotes that no offset discontinuity in the station position was anticipated from the metadata available, that is, from the station operation logfiles, which should report changes in instrumentation, or from the co-seismic displacements predicted using the earthquakes database and modelling described by Métivier et al. (2014), updated to 2020. Some exceptions to these selection criteria concerned the French GNSS stations at tide gauges, as part of the ULR commitment for France to the global sea level observing (GLOSS) programme of the Intergovernmental Oceanographic Commission (IOC, 2012).

The spatial distribution of the GNSS stations considered in ULR-repro3 is shown in Figure 1 with symbols colored according to the record length, ranging from 3 months to 21 years. The last year processed is 2020, instead of 2013 for the previous ULR reanalysis (Santamaria-Gomez et al., 2017), reaching an overall extension of seven years with a median station record length of 13.1 years. The station network shows a global distribution (Figure 1) with stations that are obviously far from coastlines: they were added from the IGS repro3 station priority list as reference frame stations to ensure an optimal alignment to the International Terrestrial
Reference Frame (ITRF) and estimation of the satellite orbits. The ULR-repro3 station network ultimately consists of 601 GNSS stations (Figure 1).

Figure 1: Spatial distribution of the 601 GNSS stations in ULR-repro3 and record length (colorbar), whose median is 13.1 years, spanning the 2000.0-2021.0 period.

2.2 GNSS processing

Estimating accurate vertical land motion from GNSS measurements involves several essential steps, such as computing daily station positions from GNSS measurements or deriving trends from the position time series. In the first step, many corrections are applied, and other parameters such as satellite orbits or atmospheric delays are adjusted along with the station positions. It requires advanced modelling and corrections (details below) and is usually best performed in a free-network approach or loosely constrained strategy (Heflin et al., 1992; Altamimi et al., 2002), whose major output is a global set of daily station positions expressed in an undetermined terrestrial frame. The next step is to align these global solutions of daily station positions to a stable and well-defined terrestrial frame such as the ITRF2014 (Altamimi et al., 2017). The last step involves modelling the kinematics described by the position time series, to obtain the quantity of interest (trends, periodic oscillations, step discontinuities, etc.). Each step involves analyst choices that can affect the estimated quantity of interest, and subsequently the geophysical interpretation. The details below can thus be crucial to understand the results and their uncertainties.
2.2.1 Modelling & Corrections

The ULR-repro3 processing considered the advances that occurred over the past seven years, since the second IGS reanalysis campaign (Rebischung et al., 2016). It complies with the highest international standards, which were adopted by the IGS for the third reprocessing campaign (http://acc.igs.org/repro3/repro3.html). The new modelling and corrections were implemented in the GAMIT/GLOBK software packages (Herring et al., 2015; 2018) used here, in particular the International Earth Rotation and Reference Systems Service (IERS) linear pole model adopted in 2018 and the high-frequency (subdaily) Earth Orientation Parameters (EOP) tide model from Desai and Sibois (2016). Table 1 provides a summary of the main modelling features and corrections applied in the ULR-repro3 reanalysis.

Table 1: Main features of the GNSS data analysis strategy adopted for ULR-repro3 following the IGS recommendations (http://acc.igs.org/repro3/repro3.html).

<table>
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<th>ULR-repro3 modelling and corrections</th>
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<tr>
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<td>Elevation cut-off angle</td>
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The remaining aspects of the ULR-repro3 data analysis strategy align with the approach used in Santamaria-Gomez et al. (2017), so the following only briefly outlines them to understand the analyst choices for geophysical application and interpretation. For each network of stations, double-differenced GPS phase observations were processed in the ionosphere-free L1/L2 linear combination. To minimize the impact of mismodeled low-elevation tropospheric delays,
satellite observations below 10 degrees were not considered. This cut-off angle aims to mitigate the limitation due to ground antennas without absolute calibration (13% of the antennas in the ULR-repro3 network), converted from relative to absolute considering only elevation-dependent phase center variation (PCV) down to 10 degrees. For the other (calibrated) GNSS antennas, phase center offsets with azimuth-dependent and elevation-dependent absolute PCV corrections were applied (igsR3_2135.atx; IGS Mail by A. Villiger, 2020). Satellite-specific antenna phase center offsets and block-specific nadir angle-dependent absolute PCV were applied for the transmitting antennas.

The first-order ionospheric delays were removed using the ionosphere-free linear combination observations, whereas the second and third orders were corrected using the International Geomagnetic Reference Field model (Alken et al., 2021) and total electron content maps from the IGS IONEX files. For the tropospheric delays, a priori hydrostatic zenith delays at the ellipsoidal surface were obtained for each station from the VMF1 grids (Böhme et al., 2006). They were then reduced to the station heights using the GPT2 model (Lagler et al., 2013). The residual zenith tropospheric delays were adjusted at 1-hr intervals (i.e., 25 parameters per day) for every station using a piecewise linear model, assuming the unmodeled wet component dominates. Both the hydrostatic and wet zenith tropospheric delays were mapped to the observation elevations using the VMF1 functions. The azimuthal asymmetry in the tropospheric delay was accounted for by estimating a linear change in gradients (north-south and east-west) over each day and station using the mapping function from Chen and Herring (1997).

The phase observations were weighted by elevation angle in the first iteration, and then by elevation angle and station-dependent scatter of the phase residuals obtained from the first iteration. The double-differenced phase ambiguities were adjusted to real values except when they could be confidently fixed to integer values (more than 85% fixed). Within the same inversion, GNSS satellite orbital parameters were adjusted using 24-hr arcs, IGS orbits as a priori values and loose constraints consistent with the station position constraints (free-network approach). Non-gravitational constant and once-per-revolution accelerations on the satellites were adjusted too, using the ECOMC model (combination of the ECOM1 and ECOM2 models (Springer et al., 1999; Arnold et al., 2015) with specific parameters constrained in post-processing). Nominal satellite attitude corrections were applied, except during eclipse periods where yaw rates were modelled (Kouba, 2009). Phase rotations due to changes in the satellite antenna orientation away from the Earth-pointing direction were also applied (Wu et al., 1993).
Regarding the Earth orientation parameters (pole position, rate and length of day), these were estimated daily with a priori values from the IERS Bulletin A. Modeled diurnal and semi-diurnal terms were added to the a priori pole and UT1 values following the IERS Conventions (Petit and Luzum, 2010).

Note that neither loading displacements due to atmospheric tides nor non-tidal (atmospheric, oceanic, hydrology) loading displacements were corrected during the first step, which aimed at estimating daily station positions from the GNSS measurements. By contrast, the displacements of the crust due to solid-Earth and pole tides (solid Earth and ocean) were corrected following the IERS Conventions (Petit and Luzum, 2010). Crustal motion due to the ocean tide loading was corrected too, using the tidal constituents computed by EOST loading service at each station from the FES2014 model (Lyard et al., 2021).

2.2.2. Offset detection & terrestrial frame alignment

Figure 2 shows the number of stations selected for ULR-repro3 with GNSS observations available each day over the time period considered (2000.0-2021.0), ranging from 110+ to nearly 500 stations. For computational efficiency, the stations were split into several regional subnetworks, each having between 29 and 70 stations processed independently. An additional subnetwork of globally distributed stations was considered to allow the daily combination of the regional subnetwork results in a unique daily global solution. This global subnetwork was made up of IGS reference frame stations, each of which also appeared in one – and only one – of the regional subnetworks. In turn, one regional subnetwork included one IGS reference frame station at least, but could include more depending on the total number of subnetworks. Moreover, to strengthen the physical link between regional subnetworks, two stations from adjacent regional subnetworks were also included, that is, one station from one nearby subnetwork and another from another nearby subnetwork, exclusive of the stations in the global subnetwork. This network strategy has changed compared to past ULR reanalyses, benefitting from the experience of the Massachusetts Institute of Technology (MIT) IGS analysis center.
The loosely-constrained station positions and tropospheric delays for the common stations and the satellite orbital and Earth rotation parameters estimated from the subnetwork data analyses were combined using GLOBK (Herring et al., 2021) to obtain the daily global solutions, which include all stations available each day with their positions expressed in a common but yet undetermined terrestrial frame. These daily global solutions were then stacked into a long-term solution using the CATREF software package (Altamimi et al., 2018) with a time-dependent functional model that included translation, rotation and scale transformation parameters between daily and long-term frames, estimated simultaneously with the mean station positions (at the reference epoch 2010.5), annual and semi-annual signals and velocities. The scale parameters, that represent the mean height changes of all the sites, are available upon request, especially for users interested in global sea level rise.

Note that position offset discontinuities (mostly due to equipment changes and earthquakes), as well as station velocity changes and post-seismic displacements, were added to the above modelling, where appropriate. Since experimented analysts still tend to perform better than automatic methods (Gazeaux et al., 2013), the position offsets were identified and adopted by expert eyeball using all positioning components (i.e., including north and east components). To facilitate this task, the equipment changes reported in the GNSS station logs were considered, as well as the co-seismic displacements larger than 2 mm predicted with the earthquakes.
When a position discontinuity was detected in a time series, the station position was estimated separately before and after the discontinuity together with the offset amplitude. The velocities before and after each position discontinuity were tightly constrained (0.01 mm/yr), unless a velocity discontinuity was suspected. In the latter case (less than 2% of the GNSS stations considered in ULR-repro3), no constraint was applied and different velocities were estimated for each period of data around the discontinuity.

The above procedure also included manual editing to identify (and remove) outliers as well as additional non-documented position offset discontinuities. It was iterated until convergence (expert eyeball). Overall 1.2 offset discontinuities were detected per decade, mostly caused by equipment changes (66.8%) and earthquakes (19.6%), whereas the remaining 13.6% were flagged as unknown (Figure 3) due to the lack of available metadata.

The long-term terrestrial frame, in which the estimated velocities are ultimately expressed, was finally aligned to the ITRF2014 (Altamimi et al., 2017) by applying minimal constraints to all the transformation parameters (translation, rotation, scale, and their rates) with respect to the positions and velocities of a stable subset of about 35 well-distributed reference frame stations. This step resulted in daily position time series expressed in the ITRF2014 frame for all (601) stations considered in ULR-repro3. From this set of position time series, only stations having more than three years between two consecutive position discontinuities and with data gaps not exceeding 30% were retained for the next step as input.

Figure 3: Average station position offsets per decade (histogram) and offsets origin (piechart)
2.2.3. Stochastic modelling and time-correlated noise

The last step was the estimation of the parameters of interest (primarily here station velocities) and their uncertainties, where both a functional and a stochastic model were adjusted to each of the position time series from the previous step on a station by station basis. In this step, an additional and independent time series editing was considered to eliminate possibly remaining unreliable estimates from the previous step. The position estimates were compared to a running monthly median. Any epoch with a position showing a difference from the median exceeding five times the median absolute deviation in at least one component was discarded.

The stochastic model considered a linear combination of white noise and power law process (WN+PL), whose parameters (the stochastic process amplitudes and the spectral index of the power-law process) were estimated using the Restricted Maximum Likelihood Estimation method (Patterson & Thompson, 1971; Koch, 1986; Gobron et al., in press). To obtain realistic stochastic parameter estimates, non-tidal atmospheric loading (NTAL) displacements were also subtracted from the position time series prior to this adjustment, following the recommendation of Gobron et al. (2021). These NTAL displacements were obtained from the Earth System Modelling team of the German research center for geosciences in Potsdam (Dill and Dobslaw, 2013).

The functional model included an intercept, a linear trend (velocity), the position offsets identified in the previous step, three seasonal terms (annual, semiannual, and terannual), periodic terms at the first eight harmonics of the GPS draconitic year (351.4 days; Ray et al., 2008), and three fortnightly terms with periods of 13.62, 14.19 and 14.76 days (Penna and Stewart, 2003; Amiri-Simkooei, 2013). The parameters of this functional model, and their uncertainties, were estimated using the weighted least squares estimator with the inverse of the estimated WN+PL model covariance matrix as weight matrix. During the observation time span, some stations (44) recorded significant co-seismic offsets and transient post-seismic signals, in which case the modeling was further extended to include velocity changes, and logarithmic or exponential decay functions according to the observed time evolution.
2.3 Estimates of vertical land motion

2.3.1 Position time series & Vertical velocities

The GNSS products of primary interest for sea level studies are the station position time series and velocity estimates on the vertical component, as underlined in the founding charter of the IGS working group “GNSS Tide Gauge Benchmark Monitoring” (Schöne et al., 2009) and later on in the implementation plan of the GLOSS programme (IOC, 2012). In the following, we focus on the vertical positioning component. However, the horizontal components are available too, and can be useful for other geophysical applications. Figure 4 shows the ULR-repro3 vertical velocity field, and the corresponding uncertainties. This GNSS velocity field ultimately consists of 546 stations, among which 457 are within 15 km from a tide gauge. This number decreases to 135 for stations less than 1 km from a tide gauge. Note that the stations inland are IGS reference frame stations (section 2.1).

Figure 4: Vertical velocities (a), and associated uncertainties (b), estimated for the stations with at least 3 years of continuous measurement (see text).
Overall, the geographical patterns observed in Figure 4.a are consistent with known geophysical processes such as uplift in the northern latitudes of Europe and America due to Glacial Isostatic Adjustment (GIA), or subsidence along the northern coastlines of the Gulf of Mexico primarily driven by ground water depletion and sediment compaction, also observed in previous and independent GPS analysis results (e.g., Blewitt et al., 2018; Hammond et al., 2021). Stations with velocity discontinuities are not plotted in Figure 4.

### 2.3.2 Data availability

The ULR-repro3 products are available from the online Digital Object Identifier (DOI) landing page (https://doi.org/10.26166/sonel_ulr7a; Gravelle et al., 2022). That is, the station position time series together with the estimated velocities for all positioning components (north, east, and up). These products are hosted at the SONEL scientific service, which serves as data assembly center dedicated to GNSS data at tide gauges (Wöppelmann et al., 2021) for the international GLOSS programme (IOC, 2012). As a UNESCO-related programme, the service complies with the UNESCO open access data policy (i.e., the data sets are available free of charge without any barriers) and strives towards providing the highest international standards, in particular in terms of long-term availability and permanent access. Note that the ULR-repro3 reanalysis yielded other parameter estimates, which can be of interest to other geophysical applications (e.g., station position offsets related to earthquakes and seasonal signals). These are also made available via SONEL.

### 3 Products quality

#### 3.1 Average time correlation properties

Previous studies have documented the presence of both power-law noise and white noise in GNSS station position time series (e.g., Williams et al., 2004; Santamaria-Gomez et al., 2011; Gobron et al., 2021; Santamaria-Gomez & Ray, 2021). Such time-correlated properties are also observed in Figure 5 for ULR-repro3, where Lomb-Scargle periodograms of all detrended station positions time series were averaged. In logarithmic scales, the power-law process induces the negative trend at low frequencies (that is, a spectral power \( \propto 1/f^\alpha \)), whereas the white noise causes the flattening at high frequencies. This flattening is especially visible above 22.8 cpy, where the power of the white noise exceeds that of the power-law process.
3.2 Stochastic properties of position time series

As the periodogram does not provide information about the properties of individual stations, the parameters, namely, the stochastic process amplitudes and the spectral index, the WN+PL stochastic models adjusted to the individual vertical position time series are presented in Figure 6.

The median value of the spectral indices is -0.93, that is, close to -1.00, which confirms the prevalence of a flicker-like noise in the low frequency band. The spectral indices show no clear latitudinal dependency (Figure 6.g-h). Since power-law amplitudes depend on the spectral index values, they were transformed into a modified empirical standard deviation (Gobron et al., 2021), expressed in mm, enabling a more rigorous comparison between noise amplitudes and Root Mean Squared Errors (RMSE) values. No latitudinal dependency is revealed in Figure 6.e. By contrast, the white noise amplitudes show largest values within the tropical band (Figure 6.c), and lower values at high latitude, but mostly non-zero thanks to the NTAL corrections (Gobron et al., 2021). Logically, this pattern also appears in the RMSE (Figure 6.a), as it quantifies the combined influence of the white noise and power-law processes.
Figure 6: Vertical position time series RMSE (a) and (b), white noise amplitudes (c) and (d); modified power-law amplitudes (e) and (f); and spectral indices (g) and (h). See text for details.
3.3 Vertical velocity uncertainties

An important consequence of temporally correlated noise in time series of GNSS positions is its impact on the uncertainties of GNSS-derived velocities, which can be largely underestimated, up to a factor of ten (Williams et al., 2004), if the temporal correlations are ignored. Figure 7 shows the distribution of the vertical velocity uncertainties obtained for the ULR-repro3 stations considering the stochastic properties estimated above. Their median value is 0.27 mm/yr with 83\% of the stations displaying a vertical velocity uncertainty below 0.5 mm/yr. The coloring in Figure 7.a indicates that the largest velocity uncertainties typically correspond to the stations with the shortest records.

![Vertical velocity uncertainties](image)

**Figure 7:** Vertical velocity uncertainties as a function of the geographical latitude with color corresponding to the record length (a) and histogram (b).

3.4 Highlights wrt previous ULR reanalysis

To appraise the progress accomplished with the ULR-repro3 reanalysis, the position time series from the previous reanalysis (Santamaria-Gomez et al., 2017) were retrieved at SONEL, and the same processing (last step in section 2) was applied for a rigorous comparison (same non-tidal atmospheric loading corrections, and same functional and stochastic models). This comparison involved the 251 common stations. Figure 8 indicates a substantial reduction of 28\% in the median vertical velocity uncertainties, from 0.35 mm/yr down to 0.25 mm/yr (ULR-repro3), which is below the uncertainty threshold reported by Griffiths and Ray (2016) using simulations to investigate the effect of position offsets and record lengthening. However, it is worth noting that the community interested in monitoring vertical land motion at tide gauges tend to limit changes in GNSS equipment to the strict unavoidable (failure, destruction, etc.) as recommended by the IGS-related working group (Schöne et al., 2009). As a result, the average
return period of offsets is about four years longer here (Figure 3) than observed for the entire set of stations contributing to the IGS repro3 campaign (Rebischung et al., 2021), hence partly explaining the improved velocity uncertainties observed with ULR-repro3 reanalysis.

Figure 8: Vertical velocity uncertainties for ULR-repro3 wrt the previous ULR solution based on the 251 common stations. The vertical dashed lines correspond to the medians.

The marked improvement in the quality of ULR-repro3 products can also be appraised from the RMSE position residuals (median value of 5.3 mm down to 4.9 mm now) and the amplitude of white noise (from 3.4 mm to 2.8 mm), whereas the power-law amplitude and spectral index remained equivalent (3.8 mm and -0.93, respectively).

4 Concluding remarks

This paper has presented the latest GNSS data reanalysis carried out by the ULR group within the international IGS framework, yielding time series of position estimates to measure the vertical land motion nearby tide gauges. It includes an increased number of GNSS stations with an extended time span. Along with the velocity estimates, their uncertainties were obtained by modelling the temporally correlated noise processes inherent in the data, after correcting the position time series for non-tidal atmospheric loading displacements, as recommended by Gobron et al. (2021). Overall, the comparisons indicate that ULR-repro3 represents a marked improvement in its products quality over the previous reanalysis, with a notable reduction in median velocity uncertainty by 28% (Figure 8).
An interesting perspective will be to examine the differences with global reanalyses obtained by other groups complying with the latest IGS standards, but using different analyst choices at any of the major GNSS processing steps described in section 2 (e.g., Blewitt et al., 2016; Männel et al., 2022). A related perspective will be to address the issue of which reanalysis is best for the non-expert sea level user, if any (Ballu et al., 2019). In this respect, the Commission on mean sea level and tides from the International Association for the Physical Sciences of the Oceans (IAPSO) could provide a stimulating framework to gather experts and users worldwide, and reflect on the issue posed by multiple high-quality GNSS reanalyses, as IAPSO did nearly thirty years ago when the issue of geodetic fixing of tide gauge benchmarks was considered with the advances of space geodesy (Carter et al., 1994).

Acknowledgments

This study was financially supported by the CNRS/INSU research agency via the SONEL & RENAG observation systems. Our study benefited tremendously from agencies making their data available to IGS and SONEL. The authors would like to acknowledge the crucial role played by the high-performance computing center of La Rochelle University, especially with Mozart & Thor supercomputers. Part of this research were made possible by support from NASA grant 80NSSC18K0457 and NSF grant NSF-IF-1843686. This is IPGP contribution number XXXX. We are grateful to Laurent Métivier for providing the modeled earthquake displacements and Jean-Paul Boy for the ocean tidal loading corrections.

Author contributions

The project was defined by MGr and GW as a contribution to the third reprocessing (‘repro3’) campaign of the International GNSS Service (IGS). MGr processed the GPS data with support from TH (GAMIT/GLOBK software packages, network design, and strategy for subnetwork design and orbit adjustment), ZA (CATREF software and reference frame alignment), PR (product quality assessment within ‘repro3’), and MGu (strategic use of the high-performance computing center). KG prepared the NTAL corrections, assessed the stochastic properties of the time series and produced the final velocity field. All authors contributed to the analysis and discussion of the results. The first manuscript draft was written by GW. All authors contributed to the subsequent versions, and approved the final manuscript.

Competing interests

The contact author has declared that none of the authors has any competing interests.
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