A High-Resolution Temperature-Salinity Dataset Observed by Autonomous Underwater Vehicles for the Evolution of Mesoscale Eddies and Associated Submesoscale Processes in South China Sea

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Abstract. Marginal seas are often characterized by dynamic~~usually filled with strongly varying~~ mesoscale eddies (MEs), whose~~which~~ evolution~~s~~ plays a critical~~vital~~ role~~s~~ in regulating global oceanic energy budgets~~equilibrium~~, triggering submesoscale processes with strong vertical velocity, and facilitating~~inducing high~~ biogeochemical~~stry~~ transport. However, traditional observation methods, constrained by passive sampling modes, struggle to resolve the temporal evolution of MEs and associated submesoscale processes at kilometer-scale resolutions. ~~But the temporal evolutions of MEs and submesoscale processes with several kilometers' resolutions are difficult to be measured by traditional observations with passive working mode. The a~~Autonomous underwater vehicles (AUVs) and underwater gliders (UGs)~~-~~, operating in active sampling modes~~actively observe oceanic motion~~, ~~and could~~ provide ~~us~~ spatio-temporal~~ly~~ synchronized measurements of these highly dynamic features.~~synchronization information for strongly varying MEs.~~ Here, we present a 9-year (2014-2022) high-resolution temperature-salinity dataset collected by~~of~~ AUVs/UGs ~~observations in 2014-2022~~ in the South China Sea (SCS), accessible via~~that can be downloaded from~~ https://doi.org/10.57760/sciencedb.11996 (Qiu et al., 2024b). In total, the dataset comprises 11 cruise experiments~~were conducted,~~ deploying 50 UGs and 2 AUVs, achieving ~~with~~ spatial and temporal resolutions of <7 km and <7 hours. ~~It~~ This dataset offers unprecedented insights into ME evolution life stages, covering~~s~~ the area of eddy's birth, propagation, and dissipation~~, presenting us the most complete data to investigate the evolution of MEs at different life stages~~. 40% of the data resolve submesoscale processes (<1 km, <4 hour), capturing dynamic instabilities along and across frontal zones at eddy peripheries. ~~, which provides us the dynamic characteristics of submesoscale instabilities across and along front at the eddy edge.~~ This dataset has potential in improving the forecast accuracy in physical and biogeochemistry numerical model. Much more aggressive field investigation programs will be promoted by the NSFC in future.

Keywords: Autonomous Underwater Vehicles; Mesoscale eddies; ~~submesoscale~~

Submesoscale processes; South China Sea

1. Introduction~~Background~~

Evolution of mesoscale eddies (MEs), characterized by intense~~with strong~~ geostrophic strain~~ing~~ rates, leads to the generation of submesoscale processes with ~~several~~ kilometer-scale~~,~~ spatial resolutions (McWilliams, 2016).~~,~~ This dynamic interplay requires~~necessitates~~ observational systems with high spatio-temporal synchronization and enhanced resolution capabilities. ~~They easily generate by~~MEs obtain~~ing~~ kinetic energy from large-scale currents, and subsequently~~easily~~ dissipate to submeso- or ~~smaller~~finer- scale processes ~~at~~ in the slope regions via combined shear and baroclinic instabilities (Oey, 1995; Okkonen et al., 2003). Marginal seas (such as, Gulf of Mexico, Mediterranean) are usually filled with MEs (Rossby number $R_o = U/fL \approx 0.1$), alongside~~and~~ smaller-scale processes ($R_o > 1$). ~~MEs are also numerous in the tropical marginal sea of~~The South China Sea (SCS), as a tropical marginal sea, demonstrates particularly vigorous ME dynamics (Chen et al., 2011; Wang et al., 2003; Xiu et al., 2010). These coherent vortices, ~~They have~~spanning ~~the spatial scale of~~ 50–300 km horizontally and ~~temporal scale~~persisting ~~of~~ several weeks to months, play~~ing~~ vital roles in the transport of matter and energy (Chelton et al., 2007; Morrow et al., 2004).

Contemporary observation platforms for MEs include shipborne surveys~~ship-cruise~~, satellite remote sensing, Argo float arrays, ~~mooring~~, Lagrangian drifters, autonomous underwater vehicles (AUVs), and underwater gliders (UGs)~~, etc~~. ~~These platforms have been utilized to detect variations of MEs in SCS (Table 1).~~ While ship-based observations are the most fundamental~~traditional~~ ~~methods~~ to investigate the MEs' general structures, their temporal resolution limits continuous evolution tracking~~, but difficult to track their spatiotemporal evolutions~~. Satellite altimetry~~data~~ provides comprehensive surface signatures of MEs, including spatial-temporal metrics, radius evolution, and trajectory mapping (~~i.e., temporal and spatial scales, eddy radius, tracks;~~ Chelton et al., 2011). Four primary ME generation hotspots have been identified in the SCS: southwest of Taiwan, northwest of Luzon Islands, the Xisha Islands region, and the eastern Vietnamese coastal zone (Hwang et al., 2000; Wang et al., 2003; Nan et al., 2011). ME propagation patterns (westward, southwestward, or northwestward) are predominantly governed by first-baroclinic Rossby wave dynamics (Lin et al., 2007; Xiu et al., 2010; Chen et al., 2011). Since 2002, a large number of Argos have been deployed, providing routine measurements to describe vertical structures of MEs (He et al., 2018; Table 1). However, ~~The~~ the spatiotemporal resolutions of Argo profiles are approximately 100 km and 10 days, ~~which is difficult~~remaining insufficient to capture the high-frequency variability of MEs and submesoscale processes (Table 1).

Table 1. Previous observational~~Observation~~ studies of mesoscale eddies (MEs)~~MEs~~ in South China Sea~~SCS~~.

Platforms	Authors	ME Sources
Ship Observation (CTD Station)	Dale, 1956	Cool pool near Vietnam
	Wang et al., 1987	Warm eddy near southwestern of Taiwan Islands
	Xu et al., 1997	Northwest of Luzon Islands, named Luzon cold eddy
	Li et al., 1998	A warm eddy in northeast of NSCS
	Chu et al., 1998	An eddy pair in central of SCS.
	Fang et al., 2002	Vietnam warm eddy
Satellite Observations (sea level anomaly; velocity)	Hwang et al., 2000; Wang et al., 2003; Nan et al., 2011	Topex/Poseidon altimeter data, 94 cold eddy, 124 warm eddy. Southwest of Taiwan Islands, northwest of Luzon Islands, East of Vietnam.
	Lin et al., 2007; Chen et al., 2011; Xiu et al., 2010	Radius, life cycle, tracking, seasonal and interannual variations of mesoscale eddies
	He et al., 2016	The role of ENSO on interannual variation in Luzon Strait mesoscale eddies
	He et al., 2019	MEs' influence on Chlorophyll-a
Argo; Mooring	Li et al., 2022	Vertical tilt of Mesoscale eddy
	He et al., 2018	Reconstruction data combine altimeter and Argos, revisit the three-dimensional structures of ME
	Zhang et al., 2017	By using mooring array, investigate eddy looping from Luzon Strait

Attributed to the active tracking, AUVs and UGs become more and more important tools in exploring marine environment over last two decades. They have the advantages in low cost, long-duration, controllability and reusability. Our research consortium~~group~~ has acquired~~collected~~ high-resolution spatio-temporal datasets through coordinated UG~~s~~ and AUV~~s~~ deployments across ME features. UGs became available to the marine science community in 2004, and they adjust buoyancy to generate gliding motion through water columns by a pair of wings (Rudnick ~~Bachmayer~~ et al., 2004; Caffaz et al., 2010). These UG platforms execute~~UGs moves in a~~ "sawtooth" transects~~trajectory~~ at sustained velocities of ~ ~~a slow speed of~~ 0.3 m/s, while AUVs are propeller-driven, acting as combining "sawtooth" and ~~drifting~~ "cruise" mode at the maximum speed of 1 m/s (Hobson et al., 2012). For a representative SCS ME with 100 km radius, full feature transection requires approximately 2.7 days for either platform type~~It takes around 8/3 days for an UG/AUV to pass a quasi-steady eddy with mean radius of ME (100 km) in SCS~~. Both platforms carry conductivity-temperature-depth (CTD) sensors for concurrent thermohaline structure mapping, enabling successful detection of dynamic features, ~~are installed on the UGs and AUVs to measure marine temperature and salinity environment. Hence, UGs and AUVs have been successfully used in detecting strongly varying features in some marginal seas,~~ such as the warming trend in Gulf Stream (Todd and Ren, 2023), and ~~or~~ the water mass exchanges between Bay of Bengal and Arabian Sea (Rainville et al., 2022). Our systematic observation program initiated UG deployments in 2014 (Qiu et al., 2015), and commenced AUV field campaigns in 2018 (Huang et al., 2019; Qiu et al., 2020). We present~~s~~ a consolidated 9-year dataset (2014-2022) from SCS operations, demonstrating ~~these platforms'~~ unique capabilities of these platform in resolving ME evolution dynamics and associated submesoscale processes.

2 Data-sets~~Description~~

2.1 UG and AUV ~~experiment~~ Experiment ~~sites~~ Sites

~~In contrast to the observational focuses of~~ ~~Different with Rainville et al (2022) and Todd and Ren (2023), most of our~~ Our experimental designs~~s~~ specifically targeted ME evolution and submesoscale process characterization~~aimed to detect t~~. This study employs two types of Chinese-developed underwater glider (UG) platforms: the "Sea-Wing" (Yu et al., 2011) and "Petrel" (Wu et al., 2011) ~~systems~~ ~~Two products of are~~

~~utilized in revealing the development of MEs in this study~~. Since 2014, we have conducted 11 field campaigns in the northern SCS, deploying 50 UGs and 2 AUVs to collect 13,491 ~~high-resolution~~ temperature-salinity profiles. Platform deployment parameters, including ~~The~~ the deploying time, installed sensors, and diving depths of UGs/AUVs experiment ~~were~~ are shown in Table 2. ~~More detailed information,~~ Complete mission metadata (~~including~~ vehicle serial number, waypoints, matching time, latitude, and longitude) ~~is~~ are ~~stored~~ archived in the data with *.~~NC~~ nc format. The gray shading in Table 2 highlights the UG ~~network experiments,~~arrays consisting of ~~with number of UGs~~ ≥3 units. Notably~~Such as~~, in the experiments of 2017, 2019 and 2020, more than 10 UGs were deployed to ~~detect~~ resolve the three-dimensional structures of the MEs.

Table 2. Available data sets from UG or AUV~~Information of individual UG/AUV experiment and the observing purpose.~~
ME: Mesoscale ~~Eddies~~Eddy; AUV: Autonomous Underwater Vehicle; UG: Underwater Glider.

Number	Equipment	Time	Number of Qualified Profiles	Number of Eliminated Profiles (Stage)	Number of equipment	Sensor of equipment (*: with Shipped CTD)	Diving depth of equipment	Observing Purpose
1	UG	Sept. 19- Oct. 15, 2014; 26 days	227	0	1 UG	Seabird Glider Payload CTD(GPCTD)	1000 m	Mixed layer heat budget; sea trials
2	UG	Apr. 18-Jul. 6, 2015; 78 days	1358	1(Syntax_Test)	3 UGs Network	Seabird Glider Payload CTD(GPCTD)	1000 m	Structures of ME
3	UG	Jul. 14-UG. 13, 2017 30 days	2902	99(Syntax Test)	10 UGs, Network	Seabird Glider Payload CTD(GPCTD)	300 m (3) 1000 m (7)	ME response to TC
4	UG	Apr. 22-May 23, 2018; 31 days	239	0	1 UG, Virtual mooring	Seabird Glider Payload CTD(GPCTD)	1000 m	Structures of ME
5	UG	Jul. 13- Sept. 30, 2019; 77 days	3672	0	17 UGs, Network	Seabird Glider Payload CTD(GPCTD) *	1000 m (17)	Slope intrusion of ME
6	AUV	Sept. 18- Oct. 23, 2019; 35 days	131	0	1 AUV	SBE37 CTD; DVL++	300 m	Evolution of ME
7	UG	Jun. 26- Aug. 27, 2020; 60 days	3793	7(Syntax Test)	12 UGs	Seabird Glider Payload CTD(GPCTD)	1000 m	Slope current
8	UG	Jul. 26- Aug. 8, 2021; 13 days	307	155(Climatology_Test & Syntax_Test);	2 UGs	RBR legato CTD	300 m (1) 1000 m (1)	Edge of ME
9	UG	Aug. 7- Aug. 27, 2021; 20 days	215	0	2 UGs	Seabird Glider Payload CTD(GPCTD)	1000 m	Edge of ME
10	AUV	May 9- Jul. 29, 2021; 80 days	168	0	1 AUV	SBE37 CTD	300 m	Evolution of ME
11	UG	Jun. 23- Jul. 6, 2022; 13 days	217	0	2 UGs	Seabird Glider Payload CTD(GPCTD)	1000 m	Edge of ME
Total	/	463 days	13229	262	50 UGs, 2 AUVs	/	/	Structures and evolution of ME

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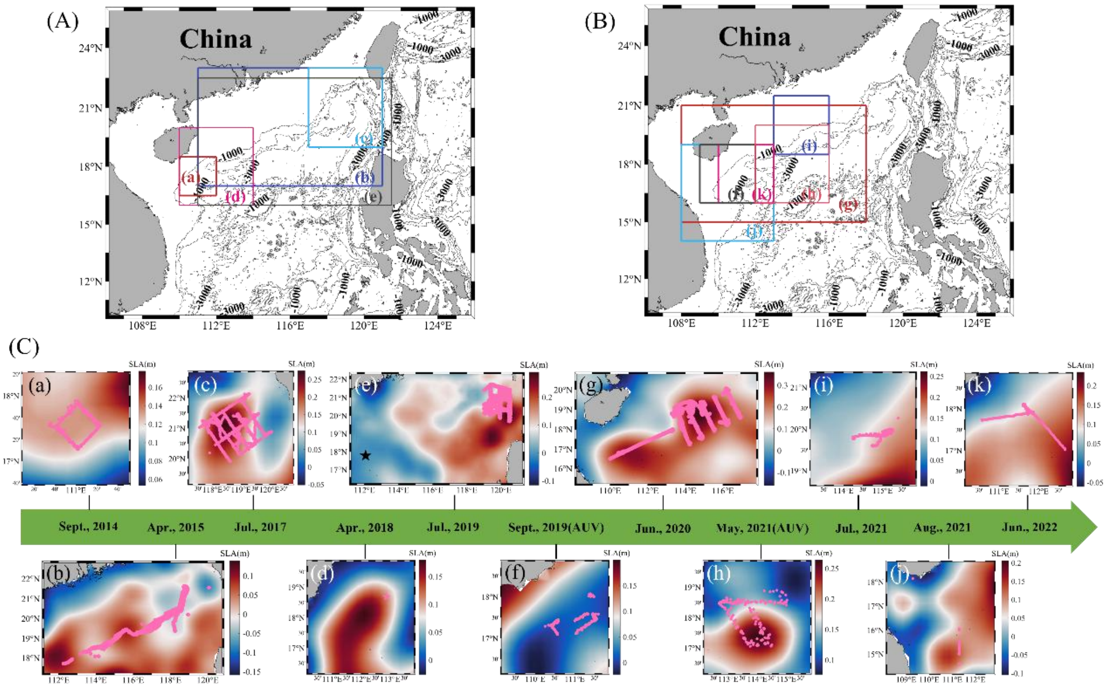

Figure 1. Underwater glider (UG) and autonomous underwater vehicle (AUV) observation sites. (A) observation area for subplots (a)-(e); (B) area for subplots (f)-(j). The grey lines in (A) and (B) are the water depth. (a)-(j) Observation stations (pink dots) with mean sea level anomaly (~~SLA averaged over the entire duration of the campaign,~~ shading colors). The observation times are (a) September, 2014; (b) April, 2015; (c) July, 2017; (d) April, 2018; (e) July, 2019; (f) September, 2019; (g) June, 2020; (h) May, 2021; (i) July, 2021; (j) August, 2021; and (k) June, 2022.

2.2 Intercomparison of UGs~~-~~ and~~/~~ AUVs ~~resolution~~Resolution

The trajectories of AUVs and UGs are depicted in Figure 1. Each trajectory is superimposed on sea level anomaly (SLA) fields. The maximum absolute value of ~~positive/negative sea level anomaly (~~SLA~~) center~~ is the ME center. Note that all the UGs and AUVs crossed MEs. Spatio-temporal sampling characteristics are presented in Figure 2. The horizontal resolution reveals two distinct regimes: 4-7 km resolution dominated 2014, 2015, and 2019 campaigns (blue histograms), while sub-3 km sampling was achieved in other years. Temporal sampling intervals exhibited similar bimodal distribution, reaching optimal 1-2 hour cadence during the 2017, July 2021, and 2022 deployments (Figures 2c, 2f, 2h), compared to 4-7 hour cycles in remaining experiments. This observational matrix demonstrates that 100% of datasets resolve ME-scale dynamics (50-300 km spectral range), while 40% of campaigns attained sufficient resolution to capture submesoscale features (<3 km characteristic scale) through synergistic AUG/AUV coordination.

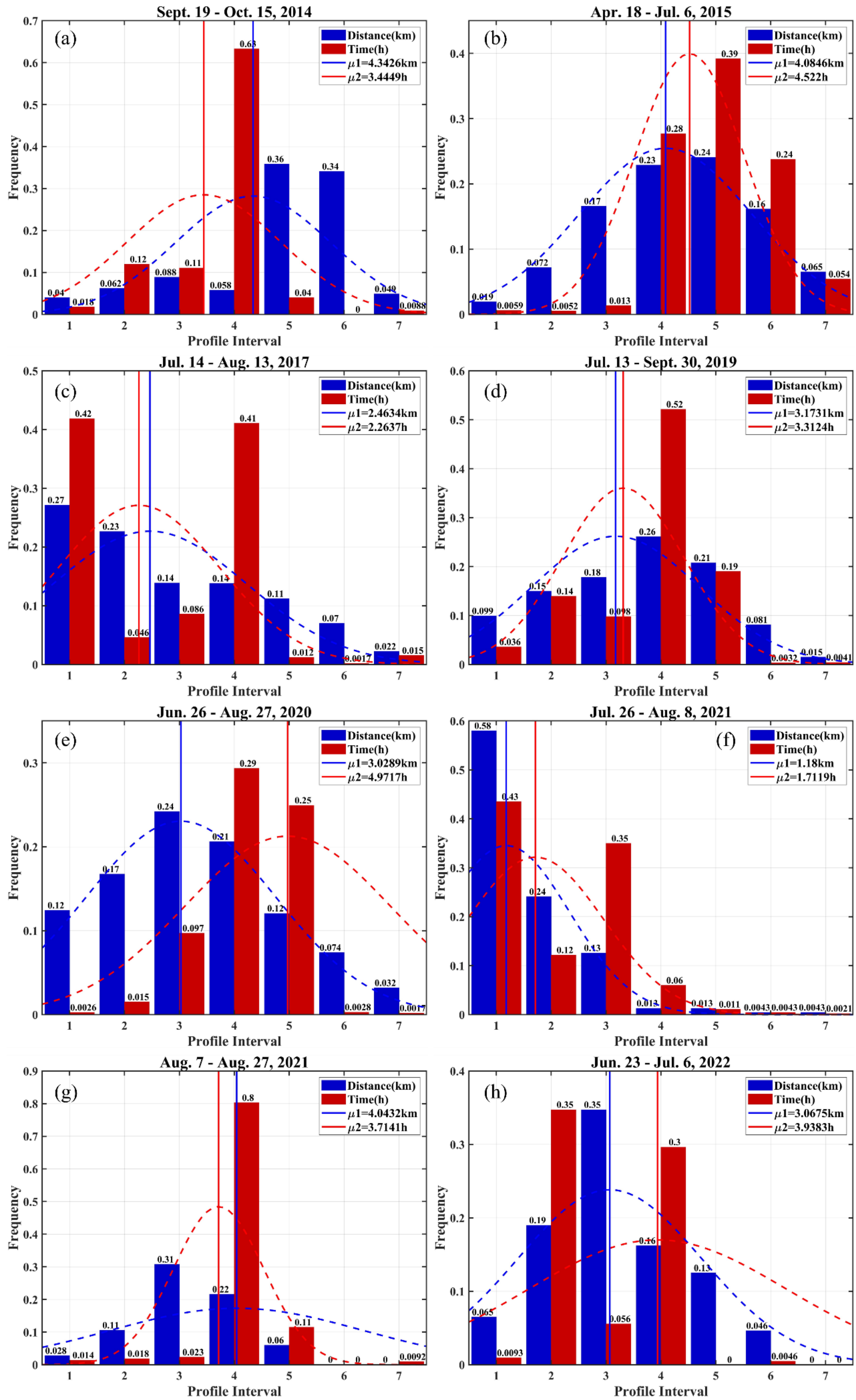

Figure 2. Frequency of spatial (blue bar) and temporal (red bar) sample interval. “Profile interval” ~~in ‘x-axis’~~ indicates the spatial interval (red) and temporal interval (blue). Bars are the probabilities. Dashed lines are normal distributions of spatial interval (red) and temporal intervals

(blue). Mean values of spatial and temporal intervals are depicted in red and blue solid lines.

3 Data Quality Control Method

~~Before~~ Prior to investigating the three-dimensional structures of MEs, we did rigorous data quality-control (QC) for the UGs and AUVs datasets.

3.1 UG ~~data~~ Data Quality Control

Two products of Chinese UGs named "Sea-wing" and "Petrel" were ~~used~~ employed in this study. These platforms integrate communication and navigation subsystems comprising: ~~contain~~ iridium satellite communication devices, wireless communication devices, a precision navigation attitude sensor, a Global Positioning System (GPS) device, a pressure sensor~~meter~~, ~~and~~ an obstacle avoidance sonar and~~.~~ a~~A~~ CTD sensor with 6-second sampling interval~~temporal resolution~~ ~~∼6 s sampling resolutions has been installed on the two UG products~~.

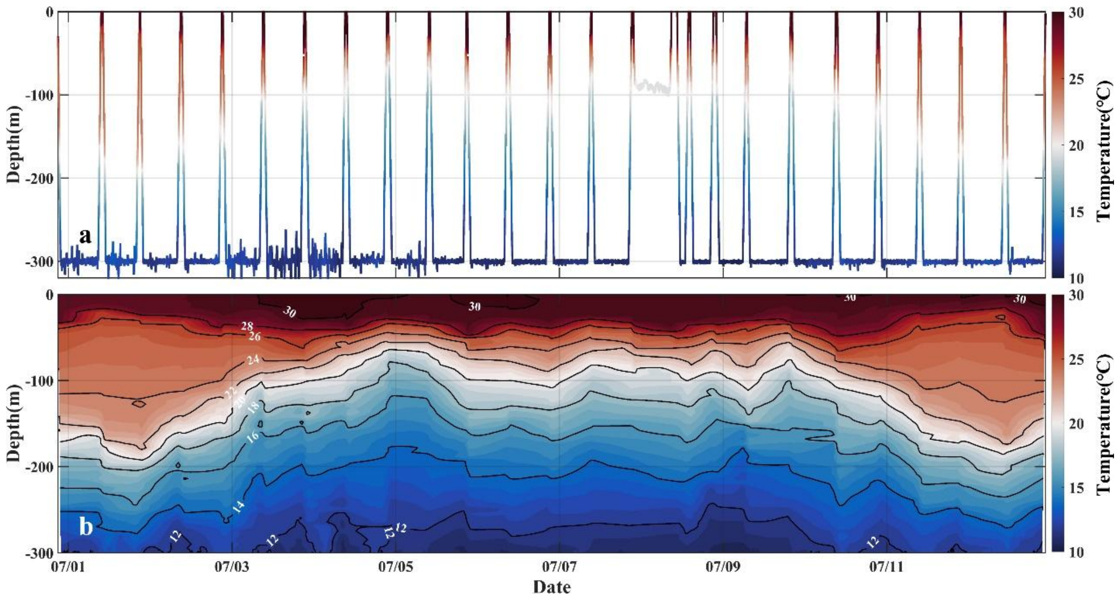

Figure 3. Illustration of (a) original, and (b) interpolated data after quality control. The AUV duration is in July 2021. AUV: autonomous underwater vehicle.

Before investigating oceanic phenomena, we did data quality control following the standard of integrated ocean observing system (IOOS). The ~~quality control~~QC procedure for UG (https://repository.oceanbestpractices.org/handle/11329/289?show=full) includes 9 steps: ~~-~~(1) Timing/Gap Test: T~~T~~est determines that the profile has been received within the expected time window and has the correct time stamp; (2) Syntax Test: Ensures the structural integrity of data messages; (3) Location Test: Test if the reported physical location (latitude and longitude) is within the reasonable range determined by the operator; (4) Gross Range Test: Ensure that the data points do not exceed the minimum/maximum output range of the sensor; (5) Pressure Test: Test if the pressure records increase monotonically with depth, sorted the vertical depth values and removed any duplicate depth values; Data after steps (1)-(5) are directly output from UGs. (6) Climatology Test: Test if the data points are within the seasonal expectation range; (7) Spike Test: Test if the data points exceed the selected threshold compared to adjacent data points, excluded the data with temperature/salinity larger than 35 °C/35 psu. ~~In steps (6) & (7), we exclude abnormal values of temperature/salinity, and produce data named "*_RO" ;~~ (8) Rate of Change Test: Test if the rate of change in the time series exceeds the threshold determined by the operator; (9) Flat Line Test: Test for continuously repeated observations of the same value, which may be the result of sensor or data collection platform failure. ~~Then the data beyond three standards deviations of steps (8)-(9) are excluded. These data were produced and named "*_TSD".~~ Post-Stage (6) & (7) data are designated as *_RO (Remove Outliers), while Stages (8)-(9) outputs generate *_TSD (Triple Standard Deviation) following 3σ outlier exclusion.

We ~~have~~ performed cross-~~validated~~ validation using the UG observed temperature and salinity profiles ~~with~~ and shipborne CTD casts~~observed~~ data during July~~,~~ 2019 (black star in Figure 1e; Figure 4). Quantitative analysis revealed ~~The~~ the mean bias of temperature is 0.05 °C, and that of salinity is 0.01 psu. The vertical temperature/salinity profiles observed by ship and UG ~~installed CTD~~ are consistent, supporting that the data are credible.

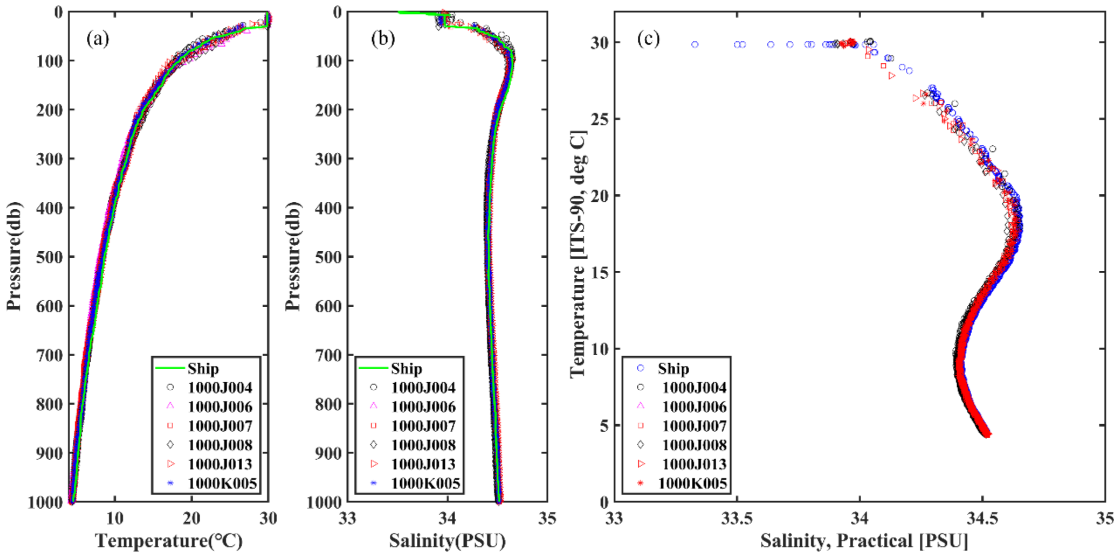

Figure 4. Comparison of (a) temperature, (b)salinity, and (c) temperature-salinity scatter plots between ship installed CTD and AUV installed CTD at station (112.0661°E, 17.7778°N). ~~Red~~ Green line in (a) and (b) is the ship measured values. Dot, ~~green~~ pink triangle, red square, diamond, red triangle, and blue star are for UGs named 1000J004, 1000J006, 1000J007, 1000J008, 1000J013 and 1000K005, respectively.

3.2 ~~Quality control for~~ AUV ~~data~~ Data Quality Control

Both CTD and GPS instrument were installed on the "Sea-Whale 2000" AUV. The platform ~~This AUV~~ was designed by Institute of Shenyang Automation, Chinese Academy of Sciences. It could operate in two modes: a "sawtooth" mode and a "cruise" mode at a specific depth of 300 m (Huang et al., 2019). ~~"Sea-Whale 2000" AUV carries platform, developed by the Shenyang Institute of Automation, Chinese Academy of Sciences, integrates a Conductivity-Temperature-Depth (CTD) sensor array and differential GPS navigation system.~~

For "sawtooth" mode data, we applied identical quality control protocols as described in Section 3.1 for UGs (Figures 3-4)~~In the "sawtooth-like" mode, the data quality control procedures are the same as those for UGs. Figures 3 and 4 show the AUV observed temperature after data quality control~~. In "cruise" mode, the AUV navigates at the depth of around 300 m. Following Qiu et al (2020), we, first, ~~ly~~ transformed the temperature and salinity at depth z to those at 300 m using a linear regression method $(T' = 0.008z' + 0.017; S' = -0.0002z' + 0.0006)$,

$$T' = T_z - T_{mean}, \tag{1a}$$

$$S' = S_z - S_{mean}, \quad (1b)$$

where T_{mean} is averaged using a 10-point smooth average, which could maintain the spatial variations from 20 to 30 km. Depth anomaly is defined as the measured depth minus 300 m, $z' = z - 300$, and the temperature and salinity anomalies as $T'$and S', respectively. Validation against~~We compared this method with the~~ potential temperature algorithm demonstrated~~, and~~ the temperatures reconstructed~~obtained~~ at 300 m were highly consistent.

3.3 Density ~~derived~~ Derived from ~~temperature~~ Temperature and ~~salinity~~Salinity

~~The value of s~~Seawater density (ρ, in kg/m^3) ~~can be calculated~~was computed based on temperature (T in °C), salinity (S in psu), and pressure (P in dbar) using the UNESCO international equation of state (Fofonoff and Millard, 1983). The UNESCO formula provides a simplified approach to estimate seawater density as follows:

$$\rho(S,T,P) = \frac{\rho_0(S,T)}{1 - \frac{P}{K(S,T,P)}} \quad (2a)$$

$$\rho_0(S,T) = \rho_{sw}(T) + (b_0 + b_1 T_{68} + b_2 T_{68}^2 + b_3 T_{68}^3 + b_4 T_{68}^4)S + (c_0 + c_1 T_{68} + c_2 T_{68}^2)S\sqrt{S} + d_0 S^2 \quad (2b)$$

$$\rho_{sw}(T) = a_0 + a_1 T_{68} + a_2 T_{68}^2 + a_3 T_{68}^3 + a_4 T_{68}^4 + a_5 T_{68}^5 \quad (2c)$$

$$T_{68} = T \times 1.00024 \quad (2d)$$

where $K(S, T, P)$ is secant bulk modulus, a_0 and others are coefficients. Coefficients follow the original formulation accounting for nonlinear compressibility effects.~~This formula accounts for the haline and thermal contraction of seawater. The detailed method is as per Fofonoff and Millard (1983).~~

4. Data Application

4.1~~Intra-thermocline (~~Subsurface~~)~~ MEs ~~observed~~ Observed by UGs and AUVs

Glider arrays successfully captured full-depth thermohaline signatures of both warm and cold eddies through cross-eddy transects (Figure 4). In April 2015, one UG deployment crossed a warm eddy, and observed a subsurface warm core (Figures 1b &

5a), corresponding to the subsurface eddy (50-500 m depth, 100 km radius) as described by Shu et al. (2016).~~. The warm core ranges from 50-500 m depth with horizontal radius about 100 km, which is termed as intra-thermocline anticyclone and has been reported in Shu et al (2016).~~ Qiu et al (2019) utilized ~~the same experimental~~this dataset to investigate the asymmetry structures of this ~~intra-thermocline~~subsurface eddy, suggesting that the centrifugal force should be taken into account when revealing the velocity of MEs, i.e., gradient wind balance theory. ~~This gradient wind theory has been cited in a deriving global cyclogeostrophic currents data (Cao et al. 2023).~~ June 2020 glider observations captured a subsurface cold eddy exhibiting pronounced thermohaline anomalies within the main pycnocline layer ~~In June 2020~~ (Figures 1g & 5d-f). This density-compensated structure, defined as local deviations from zonal mean conditions, manifested through compensating temperature and salinity anomalies that generated a baroclinic density core penetrating the upper 500 m. The colocated thermohaline signatures demonstrate UG's capability in resolving three-dimensional eddy characterization, including core localization, spatial footprint delineation, and dynamic intensity assessment.

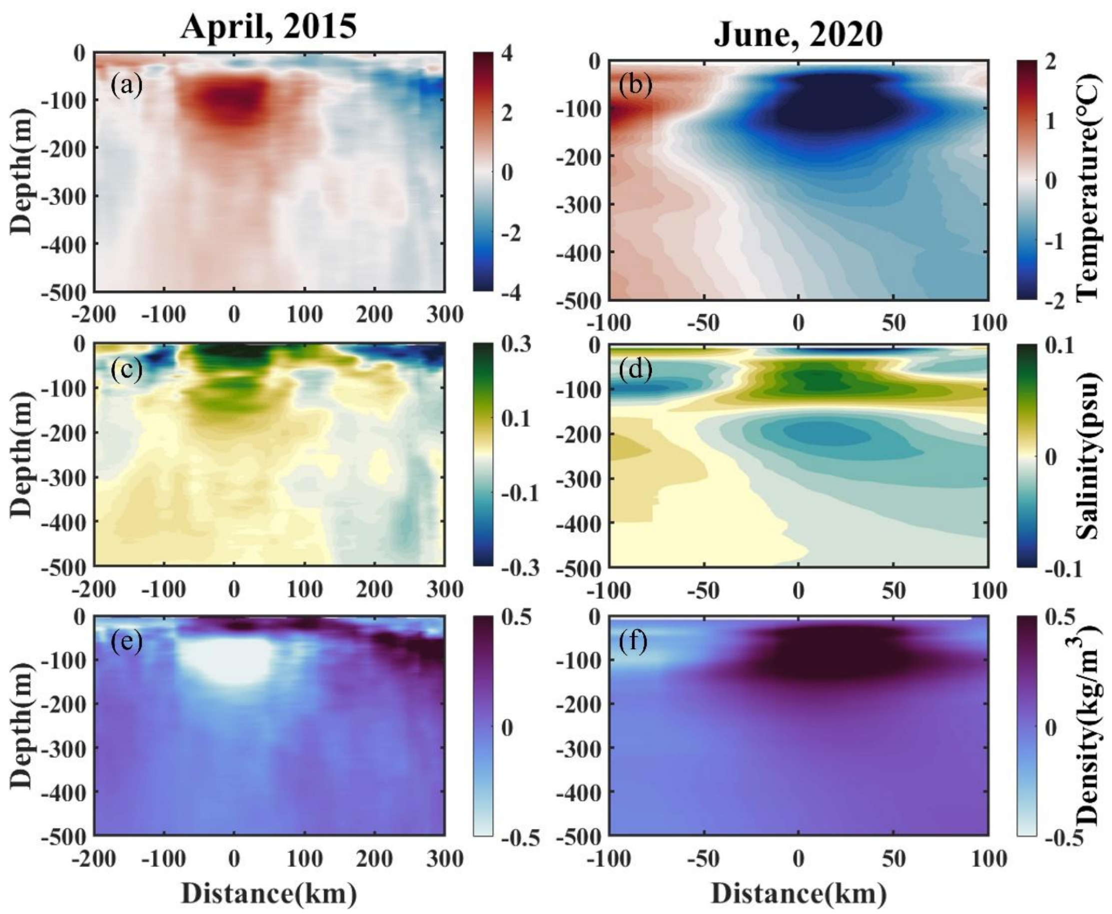

Figure 5. Contour of (a) and (b) temperature anomaly (c) and (d) salinity anomaly, (e) and (f) density anomaly in April, 2015(left panels) and June, 2020(right panels). The contours were generated using interpolation of the original data points.

Both UG and ~~/~~AUV demonstrate capability~~could~~ in ~~track~~ monitoring the temporal evolutions ~~development~~ of ~~intra-thermocline~~subsurface MEs. During their developmental~~ping~~ stages, these vortices exhibit morphological instabilities that induce cross-slope transport ~~mechanisms~~ along continental margins (Wang et al., 2018; Su et al., 2020; Qiu et al., 2022), while simultaneously generating submesoscale processes through frontal instability (Dong et al., 2018; Yang et al., 2019). To capture eddy evolution process~~maturation dynamics~~, we~~our research team~~ executed five successive AUV transects along rectangular trajectories across an anticyclonic ME between May and July 2021 (Figure 1h), supported by the National Key Research and Development Program. ~~To observe the development of ME, an AUV has traversed an anticyclonic ME using 5 repeated rectangular tracks from May to July 2021(Figure 1h). This experiment was supported by National Key R&D Program.~~

~~1~~Figure 6 illustrates a subsurface-intensified anticyclone occupying the 50-200 m depth stratum, exhibiting weakened stratification with reduced Brunt-Väisälä frequency squared value ($N^2 = \frac{1}{\rho}\frac{d\rho}{dz} < 10^{-4}$). The AUV mission was divided into five discrete phases: T1 (8-11 June), T2 (19-23 June), T3 (29 June-4 July), T4 (10-15 July), and T5 (21-26 July). Delineating the eddy boundaries using isopycnals at 22.5 kg m^{-3} and 23.5 kg m^{-3}, we quantified temporal variations in eddy area and thermal properties. A progressive decline in both areal extent and mean temperature occurred between T1 and T3, followed by subsequent recovery from T4 to T5, indicating distinct weakening and reintensification phases. This lifecycle aligns with Qiao et al.'s (2023) trajectory analysis documenting eastward propagation during T1-T3 and topographic trapping during T4-T5. ~~Taking 22.5 kg/m^3 and 23.5 kg/m^3 as the upper and lower boundary of the intra-thermocline ME, we calculated the area and the mean temperature within the ME. The area and mean temperature decreased from T1-T3, and then increased from T4-T5, indicating this anticyclonic eddy weakened from T1-T3 and strengthened from T4-T5. The development of this eddy has been described in detail by Qiao et al (2023), who found it moved eastward during T1-T3 and got stuck during T4-T5.~~

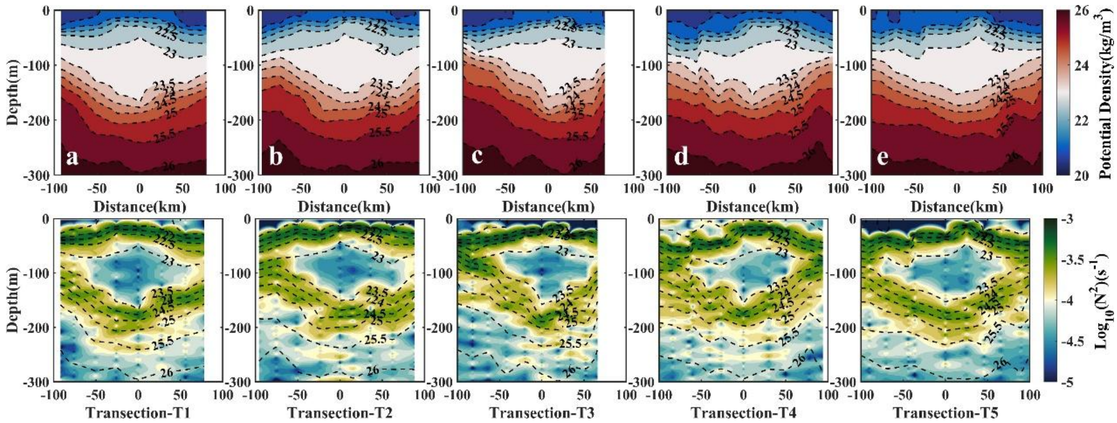

Figure 6. The profiles of density (upper panel) and Brunt frequency (lower panel) during (a,f)T1, (b,g)T2, (c,h)T3, (d, i)T4, (e, j)T5 period, which was 06/08-06/11,06/19-06/23,06/29-07/04,07/10-07/15,07/21-07/26, respectively. The contours were generated using interpolation of the original data points.

4.2 Vertical Tilt of MEs at ~~different~~ Different ~~life~~Life-stages ~~observed~~ Observed by

UGs

Coordinated glider deployments were executed in 2015, 2017, 2019, and 2020 to resolve ME dynamics. The complete ME lifecycle progresses through four distinct phases: ~~A whole life cycle of ME usually experiences~~ birth, developing, mature and dissipation~~e~~ stages (Zhang and Qiu, 2018; Yang et al., 2019), with each phase exhibiting different kinetic energy budgets. The Luzon Strait serves as an eddy birth zone where Kuroshio branch intrudes the SCS (Chen et al., 2011; Su et al., 2020). After birth, most of the eddies move westward to the continental shelf zone under the modulation of Rossby wave, finally dissipate in Dongsha Islands, Xisha Islands or merged with other eddies (Yang et al., 2019; Su et al., 2020; Qiu et al., 2022).

These deployments of AUVs and UGs enabled three-dimensional structural characterization across ME life stages. Quality-controlled temperature-salinity profiles were interpolated into 1 km × 1 km × 1 m grids prior to density (ρ) computation. ~~The systematic UG experiments provide us probability in capturing the different vertical structures of MEs at different life stages. After data quality control, we firstly mapped the temperature and salinity data onto 1 km × 1 km × 1 m grid, and then calculated the water density, ρ. The ME follows~~ Assuming geostrophic balance, ~~thus~~ the geostrophic velocity, v_g, could be derived under the force balances between pressure gradient and Coriolis forces~~. We derived the geostrophic velocity, v_g, by using thermal-wind relationships~~,

$$-v_g(x,y,z) = v_0 - \frac{g}{f\rho_0}\int_{z0}^{z}\left(\frac{\partial\rho(x,y,z)}{\partial x}+\frac{\partial\rho(x,y,z)}{\partial y}\right)dz, \qquad (3)$$

where ρ_0 is the referenced water density, f is the Coriolis frequency, and v_0 (set to 0) represents the referenced geostrophic velocity at depth 1000 m ~~and assumed to be 0~~.

The July 2019 deployment (12 UGs, 120°E) ~~Figure 7a-b depicts~~ observed the three-dimensional temperature and geostrophic velocity structures of a ME ~~(120 °E)~~ at birth stage~~, as observed by 12 UGs in July 2019 (Figure 1e&6a-b)~~, and captured~~. A~~ a subsurface warm core ~~exhibited~~ exhibiting a northeastward vertical tilt (solid black line). July 2017 observations (10 UGs, 119°E) ~~In July 2017 (Figures 1e & 6c-d)~~ revealed a developing eddy that exhibited eastward tilt through 500 m water column, which may be attributed to combined forcing from westward-propagating Rossby waves and background current shear (e.g., Qiu et al., 2015; Zhang et al., 2016; Li et al., 2019), as well as ~~and~~ thermal front advection (e.g., Bonnici and Billant, 2020; Gaube et al., 2015; Li et al., 2020). Throughout this experiment, the UGs encountered the tropical storm "Haitang", resulting in that the ME underwent horizontal deformation and giving rise to submesoscale processes (Yi et al., 2022; Yi et al., 2024).

June 2020 observations (12 gliders; ~~In June 2020, 12 UGs were deployed across an anticyclonic ME in the shelf region (~~Figures 1g and 6e-h) documented a dissipating anticyclone with southwestward tilt from 500 m to surface~~. The eddy was under dissipating stage due to the steep topography,~~ (Figure 7e-7f). This kind of southwestward vertical tilt was revealed ~~by potential vorticity~~ in a numerical model, which ~~was attributed to~~ steep topography~~shallower water depth to the west of MEs, and~~ caused asymmetries of the velocities within the MEs (Qiu et al., 2022). June 2021 AUV measurements (Qiao et al., 2023; Figure1h) further captured an eastward movement of ME, -which was dominated by wave-current interactions.

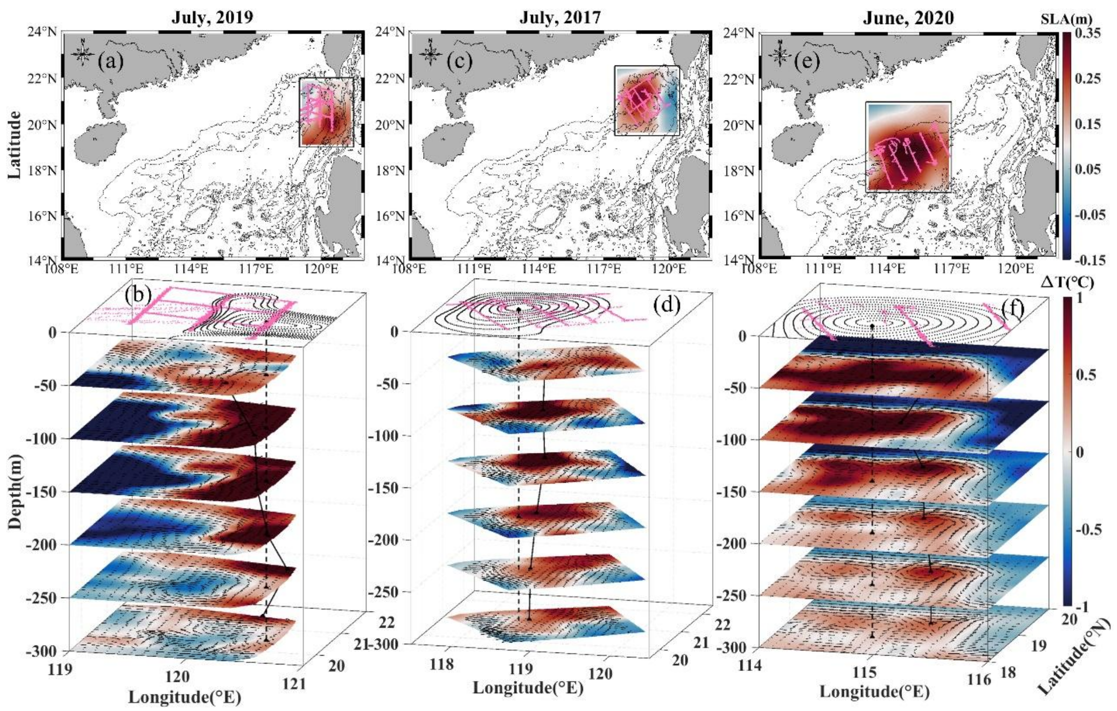

Figure 7. Eddy structures during periods of (a-b) eddy birth, (c-d) westward movement, and (e-f) dissipation along slope movements. Sea level anomaly (SLA) and UGs' positions are superimposed in upper panels (a, c, e), isobaths are represented by solid lines. The UG observed

temperature and derived geostrophic velocities are in the 3D plots (b, d, f). Pink lines are the tracks of UGs. Dashed lines denote the centers of mesoscale eddies from SLA fields, and solid dot lines are the centers from warm cores. UG: Underwater Glider. The contours were generated using interpolation of the original data points.

4.3 Submesoscale ~~instabilities~~ Instabilities at the ~~edge~~ Edge of MEs ~~observed~~ Observed by UGs

~~Smaller-scale structures, i.e., submesoscale~~ Submesoscale process, usually occurs within MEs, either at the eddy peripheries~~edge~~ (front; filament) or entrained in the eddy center, in terms of spiral structures or "eye-cat" structures (Zhang and Qiu, 2018; Ni et al., 2021; Hu et al., 2023; Qiu et al., 2024). These processes facilitate bidirectional energy transfers, driving forward cascades to dissipating~~turbulent~~ scales through symmetric and centrifugal instabilities while simultaneously energizing inverse energy pathways to MEs via mixed-layer baroclinic instabilities (i.e., Fox-Kemper et al., 2008; McWilliams, 2016). Conventional Argo floats, constrained by 10-day sampling intervals, provide insufficient data to~~prove~~ resolve~~ing~~ rather short-time scale ~~such ephemeral~~ features. Recent technological advancements reveal diverse~~divergent~~ observational capabilities. For example,~~:~~ Lagrangian platforms, like NAVIS floats, have identified frontal genesis dominated by mixed-layer baroclinic instability (Tang et al., ~~(~~2022), while glider arrays employing virtual mooring configurations achieve Eulerian frontal characterization through programmable sampling strategies (Qiu et al., ~~(~~2019;~~)~~ ~~and~~ Shang et al., ~~(~~2023). This methodological contrast highlights glider advantages in enabling simultaneous cross-front and along-front measurements through active navigation, overcoming the spatial limitations inherent to passive Lagrangian drifters.

Our observational dataset reveals that 40% of UG missions resolved submesoscale processes~~resolving capabilities~~ (<3 km horizontal resolution, <4 h temporal resolution; Figure 2). To demonstrate this operational advantage, we have analyzed two representative cases of submesoscale instabilities along ME peripheries.

The 2017 deployment illustrates multi-platform sampling strategies, with four UGs strategically positioned at an anticyclonic ME boundary (Figure 8a). Three UGs executed cross-front transects while one maintained along-front tracking, enabling comprehensive instability characterization through the Richardson number phase angle, ϕ_{Ri}, as defined, ~~as:~~

$$\phi_{Ri} = tan^{-1}\left(-\frac{1}{Ri}\right) = tan^{-1}\left(\frac{|\nabla \cdot b|^2}{N^2 \cdot f^2}\right), \tag{3a}$$

$$Ri \approx Ri_g = \frac{N^2}{\left(\frac{\partial \overrightarrow{v_g}}{\partial z}\right)^2} = \frac{N^2 \cdot f^2}{|\nabla \cdot b|^2} < \frac{f}{\zeta_g}, \text{ and } f \cdot \zeta_g > 0, \tag{3b}$$

where $b = -g\rho/\rho_0$, is the buoyancy flux, g is the gravitational acceleration. $N^2 = \partial b/\partial z$ is the vertical buoyancy frequency. $\zeta_g = curl(\overrightarrow{v_g})$ is the vertical relative vorticity (Thomas et al., 2013). For anticyclonic eddies, inertial instability or symmetric instability occurs when $-45° < \phi_{Ri} < \phi_c$. $\phi_c = \tan^{-1}(-(f + \zeta_g)/f)$ is the critical angle. Only symmetric instability occurs when $-90° < \phi_{Ri} < -45°$; symmetric instability or gravitational instability occurs when $-135° < \phi_{Ri} < -90°$; and gravitational instability occurs when $-180° < \phi_{Ri} < -135°$.

The 2017 dataset revealed coexisting gravitational, symmetric, and centrifugal-symmetric instabilities along the ME periphery (Figure 8a)~~ shows that UGs observed several types of submesoscale instabilities,~~. Figure 8b shows submesoscale instabilities in 2019. In this case, gravity instability dominates the upper mixed layer, while symmetric and centrifugal instabilities are not significant. These two cases provide us enough information to detect frontal genesis processes in Eulerian view, while NAVIS or Argos provide frontal information in Lagrange view.

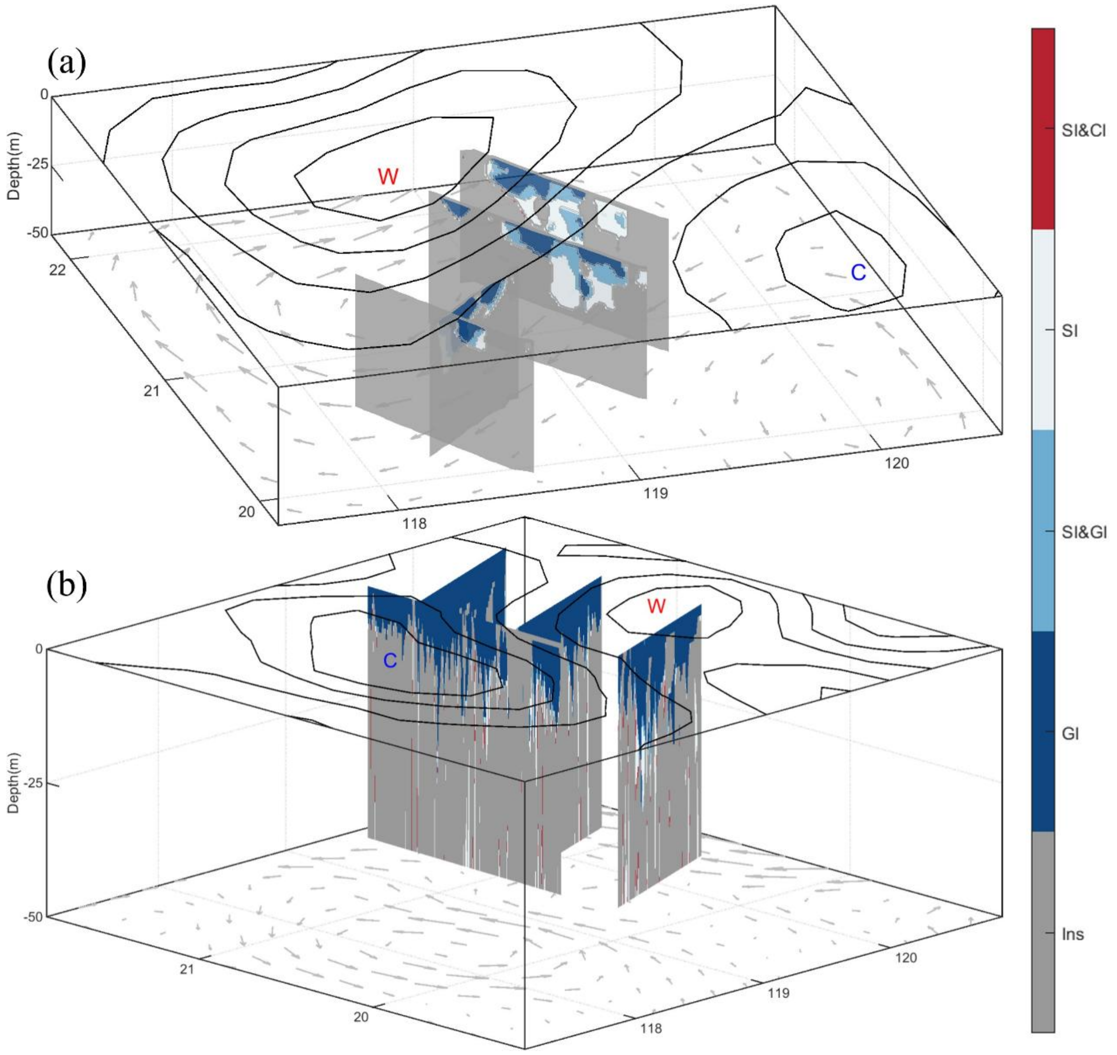

Figure 8. Analyzed submesoscale instabilities at the edge of mesoscale eddies. (a)in 2017, and (b) in 2019. SI: symmetric instability; CI: centrifugal instability; GI: gravity instability. W: anticyclonic eddy; C: cyclonic eddy. Isolines are the sea level anomaly. The contours were generated using interpolation of the original data points.

5. Data ~~availability~~Availability

The dataset of temperature/salinity observed by AUV and UG in this manuscript was deposited in Science Data Bank, whose DOI is https://doi.org/10.57760/sciencedb.11996 (Qiu et al., 2024b). The dataset includes two files of “Grid_data” and “Observation_data”.

6. Conclusions and Potential Future Plan

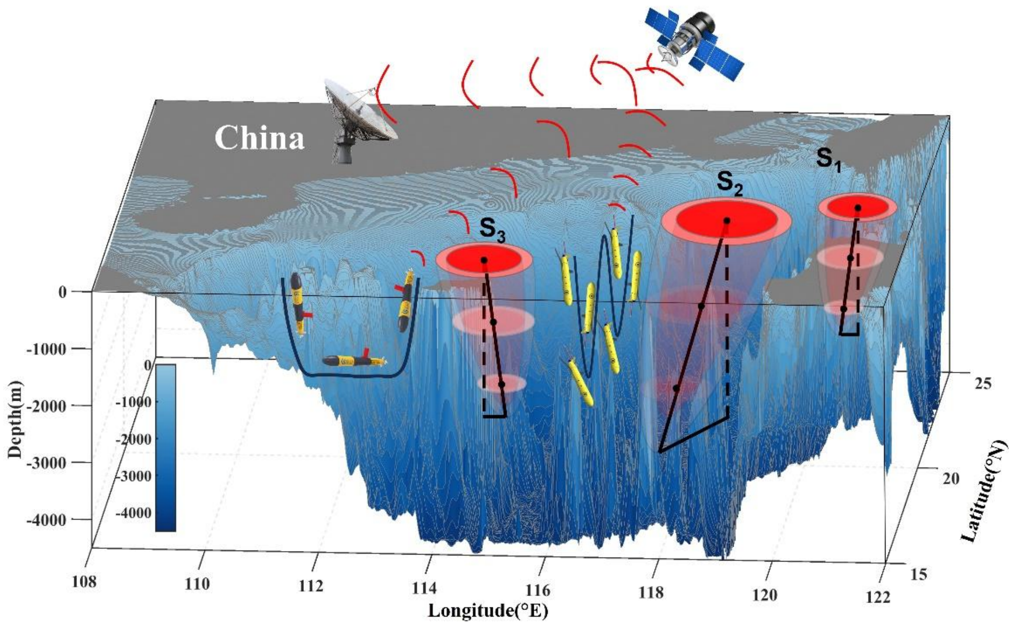

Figure 9. ~~Scheme of~~ UG operations to ~~s~~ observe~~d~~ mesoscale eddies at different life stages. ~~in the northern SCS.~~ S1: birth stage; S2: developing/mature stage; S3: dissipating stage. UG: Underwater Glider; SCS: South China Sea.

Our 9-year AUVs and UGs observations~~, we obtained~~yielded a high-resolution temperature and salinity profiles datasets in SCS. This comprehensive compilation comprises ~~The dataset provides~~ 13,491 profiles and covers 463 days' experiments, encompassing~~including~~ 11 experiments ~~from~~ deploying 50 UGs and 2 AUVs. To our knowledge, this represents the first multi-platform dataset with sufficient spatiotemporal coverage~~the 9-year dataset is enough~~ in detecting the horizontal asymmetry, vertical tilt, temporal evolution, life cycle of MEs (Figure 9), while simultaneously capturing~~and the~~ associated submesoscale processes. The dataset allows us to investigate the subsurface MEs, revealing eddy-current and eddy-topography interactions successfully. However, ~~to understand~~quantifying ~~the~~ ME feedback~~s of MEs to~~ on the variability of larger scale current, i.e. western boundary current, long-term routine UGs and AUVs observations are needed in future.

Beyond~~Besides~~ tracking MEs, UGs and AUVs have been proved to actively capture smaller scale oceanic process. Successful applications include ~~such as~~ internal tide (Gao et al., 2024) and~~,~~ turbulence by using turbulent parameterization schemes (Qi et al, 2020). Moreover, UGs/AUVs equipped with more sensors could also provide us geochemical parameters (e.g., Yi et al., 2022), ~~presenting the~~ potentially enhancing coupled physical-biogeochemical model ability ~~in improving the~~ forecasting through data assimilation. ~~accuracy in physical and biogeochemical numerical model.~~ More projects gathering AUVs network are ongoing and will be promoted in future.

Operational challenges encountered during the program include: ~~During the mission, we met some challenges:~~ (1) under strong background current, UGs and AUVs get disturbed and cannot follow the customized routes; (2) during extreme meteorological conditions, ~~bad weather makes~~ it difficult for piloting team to deploy and recovery UGs and AUVs; (3) data receiving capacity depends on the satellite transmission capacity. If both the bio-chemistry and CTD data are included, the data resolution have to be lowered. Addressing these challenges requires synergistic collaboration between field operations teams, platform engineers, and dynamical oceanographers to optimize autonomous sampling systems. ~~These challenges require piloting team and oceanographers to work together.~~

Author ~~contributions~~Contributions

Conceptualization: DX; data curation: CH, ZY, ZH, JW; formal analysis: CH, ZY; funding acquisition: CH, DX; investigation: CH, DX; methodology: CH, DX; project administration: CH, DX; software: CH, HB, DX; supervision: CH, DX; validation: XM, DX, WB; writing: CH, XM, HB. All the authors have read and agreed to the published version of the manuscript.

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Competing ~~interests~~Interests

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

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