



1 High-resolution dataset of 2024 typhoons in the
2 northern South China Sea captured by a
3 collaborative network of underwater gliders and
4 autonomous underwater vehicles

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18 Abstract: Typhoon-induced ocean responses are not only a key mechanism for
19 regulating global heat transport and maintaining the energy balance of the climate
20 system, but also the core physical processes underlying the intense exchange of matter
21 and energy at the air-sea interface under extreme dynamic forcing. However, traditional
22 passive sampling methods are limited by their discontinuous and sparse spatiotemporal
23 coverage, making it difficult to capture the complete three-dimensional structure and
24 rapid evolution of upper-ocean responses during the critical window of typhoon passage.
25 Autonomous Underwater Vehicles (AUVs) and Underwater Gliders (UGs), with their
26 active tracking and sampling capabilities, can effectively resolve the spatiotemporal
27 evolution of these highly dynamic processes. This paper presents a high-resolution
28 temperature-salinity dataset covering the passage of seven typhoons in the South China



29 Sea during 2024. Constructed from collaborative observations by 62 UGs and 2 AUVs,
30 the dataset achieves an average spatial resolution of 2.4–3.8 km and an average
31 temporal resolution of 3.5–4.3 h (99.7% of the samples had resolutions within 8.4 km
32 and 6.7 h, respectively). The dataset successfully captures the complex upper-ocean
33 temperature and salinity responses under typhoon forcing, including cooling and
34 salinity increase due to pumping, cooling and salinity decrease triggered by freshwater
35 caps formed by precipitation, cooling and salinity decrease caused by background warm
36 eddies, and significant near inertial oscillations in temperature and salinity. This dataset
37 holds significant potential for in-depth investigation of typhoon-ocean coupling
38 mechanisms and for improving the accuracy of numerical model forecasts.

39 1 Introduction

40 Typhoon-induced ocean responses, characterized by intense nonlinear
41 momentum and energy exchanges, often trigger complex multiscale
42 dynamic processes, including near inertial oscillations (NIOs), enhanced
43 vertical mixing, and restructuring of the subsurface flow field (Liao et al.,
44 2025; Mei et al., 2013; Mishra et al., 2026; Price, 1981; Reichl et al., 2024;
45 Vlasova et al., 2022; Wang et al., 2022; Zhang et al., 2021). This intense
46 dynamical coupling requires observational systems to possess high
47 spatiotemporal synchrony and enhanced resolution capabilities to capture
48 the transient characteristics of rapid oceanic responses during typhoon
49 passage. Under typhoon forcing, the wind stress energy absorbed by the
50 ocean surface primarily triggers intense vertical shear, inducing unstable
51 turbulent mixing that draws sub-surface cold water to the surface.
52 Concurrently, Ekman pumping driven by wind stress vorticity also
53 generates upwelling of sub-surface cold water. The combined action of



54 these two processes forms a distinct cold wake structure in the upper ocean
55 (John et al., 2025; Ye et al., 2023; Zhou et al., 2025). As one of the regions
56 with the highest frequency of typhoon activity globally, the South China
57 Sea’s semi-enclosed topography and complex background flow field result
58 in particularly intense and unique typhoon-ocean interactions (Guan et al.,
59 2024; Yang et al., 2022; Zheng and Wang, 2023). These typhoon-driven
60 vertical exchange processes and three-dimensional circulation
61 reconstruction play a central role in oceanic energy cascading, heat
62 redistribution, and material fluxes across isopycnal surfaces, exerting
63 profound impacts on regional climate prediction and the evolution of
64 marine ecosystems (Chen et al., 2026; Fan et al., 2023; Gong et al., 2026;
65 Wada and Yanase, 2024; Yi et al., 2024; Yu et al., 2021; Zhang, 2023).

66 Currently, the primary observational platforms for typhoon-induced
67 ocean responses include satellite remote sensing, moored buoy array, Argo
68 buoy array, Lagrangian drifter, underwater glider (UG), and autonomous
69 underwater vehicle (AUV). The extreme sea conditions triggered by
70 typhoons make it difficult to conduct traditional ship-based oceanographic
71 surveys. Satellite observations can only provide characteristics of sea
72 surface changes. They cannot characterize sub-surface dynamic and
73 thermal processes, and their insufficient temporal resolution makes it
74 difficult to resolve high-frequency wave signals (Lu et al., 2025; Zhang et
75 al., 2024a). Moored buoy arrays can provide long-term, continuous, fixed-



76 point observations and are often used to capture typhoon-induced near
77 inertial waves, but their sparse spatial distribution necessitates “stationary”
78 observations: if located too far from the typhoon, they cannot capture large-
79 scale response processes (Athulya et al., 2026; Chen et al., 2025; Tang et
80 al., 2025; Wang et al., 2021; Yang et al., 2021, 2024; Zhang et al., 2016,
81 2018). Argo buoy arrays and Lagrangian drifters can respectively record
82 the three-dimensional thermodynamic structure and ocean current response
83 induced by typhoons. However, the former’s spatial and temporal
84 resolutions of approximately 10 days and 100 km are insufficient to capture
85 high-frequency variability, while the latter cannot obtain information on
86 subsurface circulation. Furthermore, the uncontrollable nature of their
87 passive drifting poses significant challenges for data collection (Chen et al.,
88 2021; Goni et al., 2017; He et al., 2024a, b; Li et al., 2022, 2021; Liu et al.,
89 2026; Qiu et al., 2025; Ruan et al., 2024; Sala et al., 2024; Tian and He,
90 2025; Trenggono et al., 2024; Wang et al., 2022).

91 Attributed to their active observation capabilities, UGs and AUVs
92 have become essential tools for exploring the marine environment over the
93 past two decades (Qiu et al., 2025). These platforms offer advantages such
94 as low cost, long endurance, high controllability, and reusability. Both
95 platforms are equipped with conductivity-temperature-depth (CTD)
96 sensors to simultaneously acquire vertical temperature and salinity profiles,
97 enabling the successful detection of dynamic features such as the warming



98 trend of the Gulf Stream (Todd and Ren, 2023) and water mass exchange
99 between the Bay of Bengal and the Arabian Sea (Rainville et al., 2022).
100 Previously, Qiu et al. (2025) successfully acquired high spatiotemporal
101 resolution datasets by coordinating the deployment of UGs and AUVs
102 across mesoscale eddy regions, conducting systematic observations
103 primarily focused on mesoscale eddies and their associated submesoscale
104 processes. Recently, Zhang et al. (2024b) further utilized an unmanned
105 observation array comprising UGs and wave gliders to conduct
106 collaborative observations of Typhoon Koinu (2023), successfully
107 revealing the evolution of the air-sea environment within the typhoon’s
108 core region. Furthermore, the “Yunfan” hybrid wind-wave-powered
109 unmanned vessel, developed by Tian et al. (Huang, 2025), successfully
110 completed close-range observations of the core region of Typhoon Wutip,
111 transmitting key meteorological parameters such as wind speed and air
112 pressure in real time. Although the aforementioned studies have made
113 significant progress in using unmanned platforms to observe typhoons, to
114 date, there have been no reports of publicly released datasets derived from
115 observations of typhoon-induced oceanic responses using platforms with
116 active observation capabilities. Therefore, this study designed an
117 experiment specifically for observing typhoon-induced ocean responses
118 and successfully conducted comprehensive field observations in the South
119 China Sea from late May to early December 2024. This paper presents a

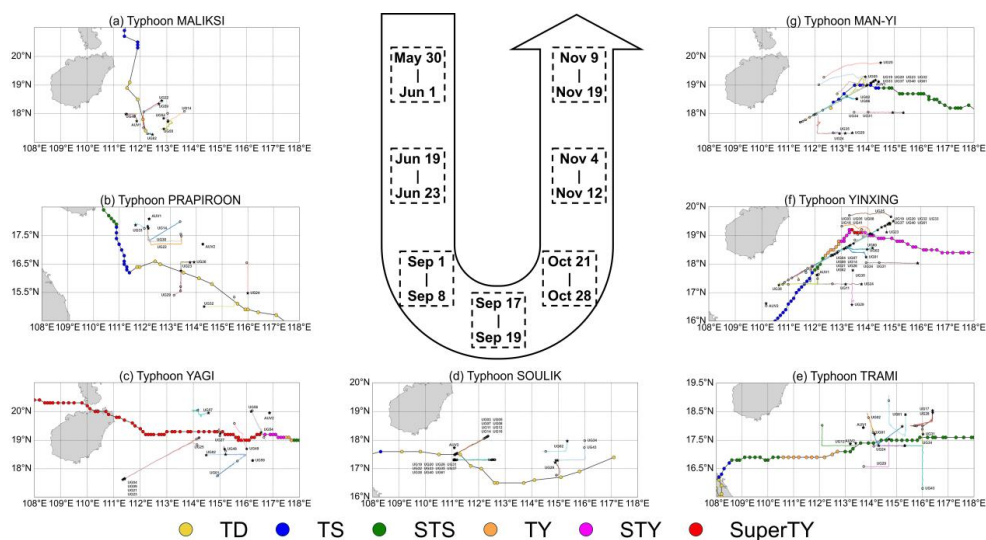


120 dataset of typhoon-induced oceanic temperature and salinity responses
121 obtained from the experiment, aiming to demonstrate and validate the
122 unique advantages and robust capabilities of UGs and AUVs in resolving
123 oceanic dynamic processes under typhoon forcing.

124 2 Datasets

125 2.1 UG and AUV experiment sites

126 The experimental design of this study aims to systematically
127 characterize the dynamic response of the upper ocean to typhoon forcing.
128 The observation platform consists of the “SeaWing” series of UG (Yu et
129 al., 2011), independently developed in China, and “SeaWhale” AUV. Field
130 observations commenced in late May 2024 and concluded in early Dec.
131 2024, spanning approximately six months. During this period, a total of 62
132 UGs and 2 AUVs were deployed, accumulating over 57,000 water
133 temperature and salinity profile data points. A total of seven typhoon events
134 were recorded during the observation window. Through spatiotemporal
135 matching analysis, 112 valid paired samples were established between
136 typhoon events and UG/AUV observation data, totaling 4,459 temperature-
137 salinity profiles. Fig. 1 shows the tracks of the UGs and AUVs. Tab. 1
138 details the deployment parameters for each platform, including operational
139 periods, sensor types carried, and maximum diving depths. Additionally,
140 complete mission metadata has been archived in NetCDF (.nc) format (Qi
141 et al., 2026).



142

143 Figure 1. Trajectory of the 7 typhoons and the UGs/AUVs. These 7 typhoons are listed
 144 in numerical order: MALIKSI (No. 2402), PRAPIROON (No. 2404), YAGI (No. 2411),
 145 SOULIK (No. 2415), TRAMI (No. 2420), YINXING (No. 2422), and MAN-YI (No.
 146 2424). The legend indicates typhoon intensity, and the dotted lines with intensity
 147 markers represent the typhoon paths. The text labels “UG” and “AUV” are placed near
 148 their respective tracks, and the “★” represents the starting point, and the “○” represents
 149 the endpoint.

150 2.2 Statistics of UG and AUV resolutions

151 During the operational period, the observation area experienced a total
 152 of 8 typical typhoon events (Fig. 1 and Tab. 1, “TY event” column), which
 153 were primarily concentrated between Sept. and Nov., exhibiting a pattern
 154 of higher frequency in the autumn. Among these, the joint observation
 155 network comprising UGs and AUVs successfully captured 7 typhoon
 156 events; only Typhoon TORAJI was not effectively observed because it was
 157 located at the edge of the observation network. Given that the deployment



158 density of UGs was significantly higher than that of AUVs, we established
159 differentiated spatiotemporal matching thresholds during the process of
160 aligning observation profiles with typhoon tracks. We used thresholds to
161 filter the entry locations and times for UGs and AUVs, the spatiotemporal
162 matching threshold for UGs was set to $\leq(3 \text{ h}, 100 \text{ km})$, while a more lenient
163 threshold of $\leq(3 \text{ h}, 150 \text{ km})$ was applied to AUVs. Statistical analysis
164 shows that during each typhoon passage, the maximum navigation distance
165 of the observation platforms exceeded 120 km (Tab. 1, “Max. trajectory
166 length” column), fully covering the typhoon passage period and achieving
167 forward deviation (Tab. 1, “Equip. Active Days” column, extending 2 days
168 before and after the passage), ensuring effective observation of typhoon-
169 induced oceanic responses.

170 A statistical analysis of the spatiotemporal sampling characteristics of
171 UGs and AUVs during typhoons was conducted. Fig. 2a and Fig. 2b show
172 the mean and standard deviation of the operational distance and duration
173 of the observation network during typhoons. The results indicate that
174 navigation activities primarily occurred at a spatial resolution of 2.4–3.8
175 km and a temporal resolution of 3.5–4.3 h. According to the 3σ principle,
176 99.7% of the data fell within 8.4 km and 6.7 h. Fig. 2c presents box plots
177 of the navigation distance and duration for a single operational cycle of the
178 observation platforms. As shown in the figure, the median navigation
179 distance for the devices during the seven typhoons mostly ranged between



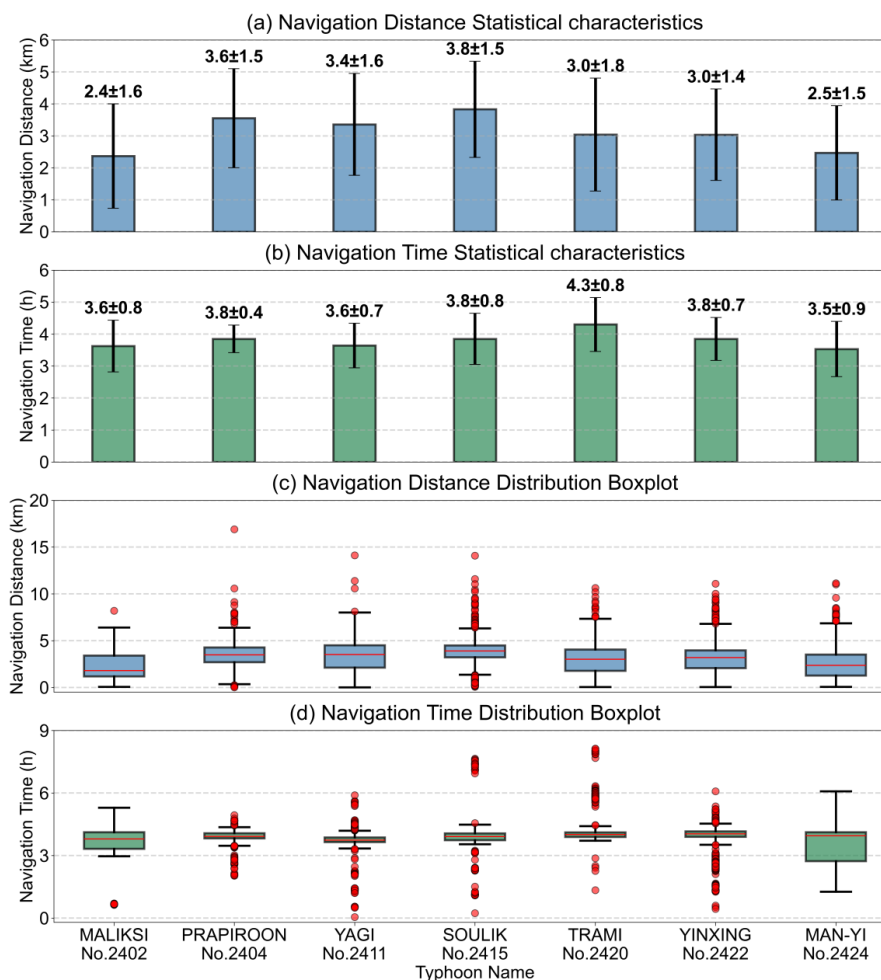
180 2 and 4 km. The steel-blue rectangular blocks representing the Interquartile
181 Range (IQR) generally have a wide height, indicating a high degree of
182 dispersion in navigation distance. Fig. 2d shows a box plot of the
183 navigation time for a single operational cycle of the observation platform,
184 indicating that the median navigation time is concentrated around 4 hours.
185 Except for Typhoons MALIKSI and MAN-YI, where the IQR (represented
186 by the sea-green rectangular blocks) is relatively wide, the IQR for the
187 remaining typhoons is generally narrow. This suggests that over 50% of
188 the observation duration is highly concentrated within 4 h, reflecting the
189 relative stability of the temporal sampling.

190 It is worth noting that there are some outliers in the navigation
191 distance box plot (Fig. 2c): these include the red dots above the boxes for
192 Typhoons PRAPIROON, YAGI, and SOULIK, with maximum navigation
193 distances reaching as far as 17 km; as well as a small number of outliers
194 with extremely short distances below the PRAPIROON and SOULIK
195 boxes (some less than 1 km). Similarly, the navigation time box plot (Fig.
196 2d) also contains a certain number of outliers (such as the red dots on both
197 sides of the boxes for YAGI, SOULIK, and TRAMI). These outliers are not
198 merely data noise, but reflect the “relatively controlled in time and random
199 in space” movement characteristics of the observation equipment during
200 typhoons, and may be a direct record of the interaction between the
201 observation platform and the complex oceanic dynamic environment



202 induced by typhoons. The outliers on the navigation distance box plot may
203 reflect the violent changes in the typhoon-induced flow field, embodying
204 the nonlinear superposition effect of the observation platform's own
205 navigation speed and the typhoon-induced flow field moving with or
206 against the current. Meanwhile, the outliers on the navigation time box plot
207 may stem from abnormal operational cycles caused by communication
208 disruptions, protective mechanisms such as deep-diving to avoid currents,
209 or adaptive attitude adjustments under extreme sea conditions.

210 The analysis of the spatiotemporal characteristics described above
211 indicates that the dataset obtained through the combined observations of
212 UGs and AUVs not only has the capability to resolve typhoon-induced
213 mesoscale (50–300 km) oceanic dynamic processes but also possesses
214 sufficient spatiotemporal resolution to capture high-frequency
215 (characteristic timescale $> 2 \times 4$ h, such as near inertial oscillations) dynamic
216 processes, thereby providing high-quality data support for a deeper
217 understanding of the typhoon-ocean interaction mechanisms.



218

219 Figure 2. Statistics on spatial and temporal sampling. (a) and (b) show the mean and
 220 standard deviation of the normal distributions of spatial and temporal sampling,
 221 respectively; the bars represent the mean, and the black lines represent one standard
 222 deviation. (c) and (d) show box-and-whisker plots of the spatial and temporal samples.
 223 The red horizontal line represents the median of the sample. The height of the box is
 224 the difference between the 75th and 25th percentiles of the data, known as the
 225 interquartile range, which encompasses 50% of the sample. The black whiskers indicate
 226 the range of variation in the sample, and the red circles mark outliers.

227



228 Table 1. Available datasets from UGs and AUVs.

No.	TY event	Equip. Active Days (2 days pre- and post-TY passage)	No. of		No. of profiles (profile) UG/AUV	Min. distance to TY center (km)	Max. trajectory length (km)	Avg. daily profiles (profile)	Avg. profiles per Equip. during TY (profiles)
			matches (unit) UG/AUV	profiles (profile) UG/AUV					
1	MALIKSI	28 May-3 Jun 2024, 7 d	7/1	302/3	24.7	128.49	43	43	43
2	PRAPIROON	17 Jul-25 Jul 2024, 9 d	9/2	440/2	16.3	140.12	48	48	48
3	YAGI	30 Aug-10 Sept 2024, 12 d	14/1	964/1	7.6	336.65	80	80	68
4	SOULIK	15 Sept-21 Sept 2024, 7 d	23/1	921/1	26.0	161.94	131	131	40
5	TRAMI	19 Oct-30 Oct 2024, 12 d	11/2	695/2	9.8	182.72	57	57	63
6	YINXING	2 Nov-14 Nov 2024, 13 d	31/2	2267/3	3.9	297.23	174	174	73
7	MAN-YI	7 Nov-21 Nov 2024, 15 d	17/1	1515/1	12.7	299.56	101	101	89
	Average	≈10.7 d	≈16/1	≈637/2	—	—	≈90	≈90	≈60
	Total	75 d	112/10	4459/13	—	—	—	—	—

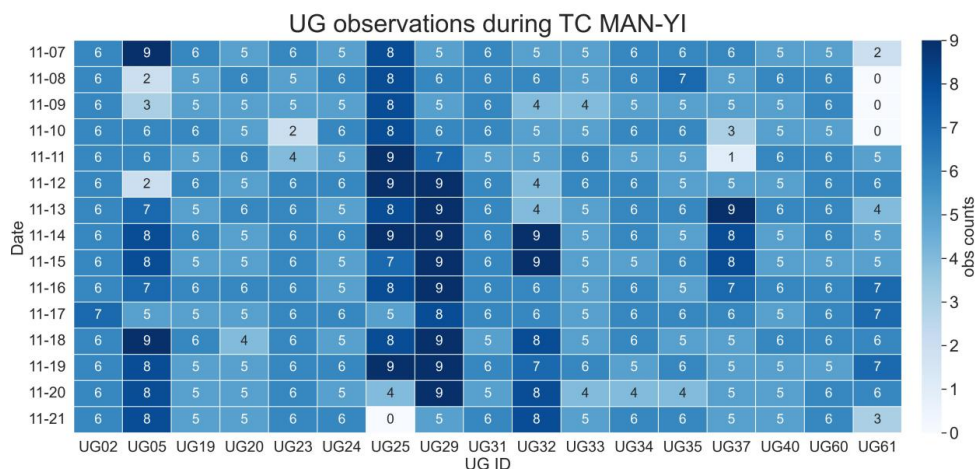
229 TY: typhoon; UG: underwater glider; AUV: autonomous underwater vehicle; Equip.: equipment.

230



231 2.3 Sampling Performance of the Observation Network During Typhoons

232 During typhoon passages, strong winds and intense oceanic
 233 disturbances posed significant challenges to glider observation operations.
 234 Among the seven typhoon events covered in this study, a total of 112 valid
 235 “typhoon-UGs/AUVs” matching records were obtained, involving 62 UGs
 236 and 2 AUVs. It is worth noting that while the vast majority of UGs
 237 participated in typhoon observations within the study area, the deployment
 238 density of AUVs was relatively low, with no more than three matching
 239 records generated per typhoon event.



240
 241 Figure 3. Heatmap of UG data collection during Typhoon MAN-YI. The x-axis shows
 242 the device IDs that detected MAN-YI, the y-axis shows the observation time, and the
 243 number of cells represents the number of temperature-salinity profiles.

244 Statistical results show that, except for Typhoon MALIKSI (No.
 245 2402), all other typhoons were detected by at least 10 observation devices.
 246 Among them, Typhoon SOULIK (No. 2415) and Typhoon YINXING (No.
 247 2422) were detected by 24 and 33 observation devices, respectively (“No.



248 of matches” column in Table 2). Taking the UGs observing MAN-YI (No.
249 2424) as an example, a total of 17 UGs recorded this typhoon event (see
250 Fig. 3). During this event, the maximum number of UG observations
251 recorded in a single day reached 110 (Nov. 14), with a daily average of no
252 less than 97; the maximum number of records from a single device during
253 the typhoon event was 114 (UG29), and the average number of records
254 from a single device was no less than 86.

255 A statistical analysis of all observation pairs revealed the following:
256 (1) In terms of temporal coverage, the average observation duration per
257 pair was approximately 10.7 days, providing complete coverage of the pre-
258 typhoon background conditions, the typhoon forcing process, and the post-
259 event recovery phase. (2) In terms of spatial coverage, the average track
260 length per mission was 153.24 km, with a cumulative total track length of
261 17,162.69 km, demonstrating the UG’s effective observational capability
262 over a large oceanic area during typhoon events. More importantly, all pairs
263 included at least one observation profile within 100 km of the typhoon
264 center, and approximately 17.2% of the pairs included profiles within the
265 25-km near-field range, indicating that some UGs were able to directly
266 observe air-sea interaction processes in the typhoon’s core region.

267 Overall, UG offers significant spatiotemporal advantages in typhoon
268 observations. On the one hand, UG is capable of maintaining continuous
269 and stable observations throughout a typhoon event, providing a complete



270 data chain for the study of typhoon-driven ocean response processes. On
271 the other hand, the combination of far-field and near-field observational
272 data allows research to simultaneously reveal the forcing mechanisms in
273 the typhoon's core and the response propagation effects in the outer regions.
274 In summary, UG observations not only demonstrate the
275 comprehensiveness of typhoon event monitoring in terms of sample size
276 and coverage but also maintain reliability under extreme near-field
277 conditions, providing a solid data foundation for understanding the oceanic
278 dynamical and thermal responses during typhoon events.

279 3 Data quality control method

280 Before investigating the response of the upper ocean to typhoon
281 processes, we performed rigorous quality control and thermal lag
282 correction on the UG and AUV datasets.

283 3.1 Data quality control

284 This study employs the “Sea-Wing” UG and ‘SeaWhale’ AUV as core
285 observation platforms. The “Sea-Wing” integrates multi-source
286 communication and navigation subsystems, including Iridium
287 communication, wireless telemetry modules, high-precision attitude
288 sensors, Global Positioning System receivers, pressure sensors, and
289 obstacle-avoidance sonar. Meanwhile, the “SeaWhale” integrates a CTD
290 sensor, a Doppler current profiler, obstacle-avoidance sonar, and a
291 propulsion module. It can perform zigzag profiling maneuvers like a glider



292 as well as cruising at a fixed depth. Oceanographic parameters are collected
293 at 6-second intervals via a non-pumped CTD sensor. Before analyzing
294 ocean phenomena, all raw data undergo rigorous quality control (QC) and
295 strictly adhere to Integrated Ocean Observing System (IOOS) standards.
296 Table 2 details the 13-step systematic QC process tailored to the specific
297 characteristics of glider data, along with the corresponding decision logic.

298 This quality control protocol effectively eliminates significant errors
299 caused by positioning drift, sensor failure, and non-physical abrupt
300 changes, significantly improving the spatiotemporal continuity and
301 physical consistency of the data. However, this process cannot resolve the
302 systematic thermal lag bias caused by mismatched response times between
303 the temperature and conductivity sensors in non-pumped CTDs. Such
304 errors often produce spurious salinity peaks, particularly when the glider
305 traverses strong thermoclines. Therefore, specialized corrections for sensor
306 dynamics are required. Section 3.2 details the physical mechanisms of
307 thermal lag effects and introduces a correction algorithm optimized for
308 variable flow rates to further eliminate residual systematic synchronization
309 errors.

310



311 Table 2. QC Protocol Steps for UG and AUV Data

No.	Test item	Purpose	No.	Test item	Purpose
1	Time/Gap	Remove invalid timestamps; fix abnormal gaps.	8	Spike	Eliminate abrupt noise using depth-dependent thresholds.
2	Location	Discard coordinates outside operational boundaries.	9	Rate of Change	Filter fluctuations exceeding local physical limits.
3	Position on Land	Remove points erroneously located on land.	10	Frozen Value	Delete sequences of constant sensor readings.
4	Displacement	Discard data with anomalous positioning drift.	11	Vertical Velocity	Remove profiles with stalled or unrealistic speeds.
5	Pressure	Sort profiles; fix depth inversions and duplicates.	12	Density Inversion	Flag layers violate hydrostatic stability.
6	Gross Range	Filter values beyond global/regional physical limits.	13	Mixed Layer Disc.	Remove non-physical jumps near mixed layer depth.
7	Climatology	Discard outliers deviating from historical means.			



313 3.2 Thermal lag correction

314 When UGs and AUVs are equipped with pump-less CTD sensors for
315 observations, a phenomenon known as the “thermal lag effect” occurs due
316 to the spatial separation and differences in response time between the
317 temperature sensor (typically located outside the conductivity
318 measurement chamber) and the conductivity sensor (located inside the
319 measurement chamber). This effect is particularly pronounced when
320 traversing regions with steep temperature gradients, such as the
321 thermocline, leading to systematic biases in derived salinity data and the
322 generation of spurious salinity peaks. Furthermore, the unstable operating
323 speeds of these platforms cause dynamic changes in the seawater flow rate
324 through the conductivity cell, thereby complicating the calibration process.
325 To address this challenge, calibration methods initially developed for ship-
326 based CTDs laid the foundation for data processing on mobile platforms.
327 Morison et al. (1994) pioneered an empirical method based on minimizing
328 the deviation in the temperature-salinity (T-S) relationship, estimating the
329 lag parameter by constraining the salinity difference between the up- and
330 down-trajectory profiles. Building on this, Garau et al. (2011) proposed an
331 optimization method for pump-less gliders, employing a sequential
332 quadratic programming (SQP) algorithm to minimize the enclosed area
333 between the up- and down-trending T-S curves, thereby obtaining optimal
334 correction parameters. Liu et al. (2015) further refined the correction



335 strategy for regions with strong thermoclines, effectively mitigating
336 salinity abrupt changes under steep gradients.

337 To eliminate salinity errors caused by thermal lag, this study employs
338 a synchronous conductivity correction method, which mathematically
339 reconstructs conductivity data to match the response characteristics of the
340 temperature sensor. The discrete recursive formula for conductivity
341 correction is expressed as:

$$342 \quad C_T(n) = -bC_T(n-1) + \gamma a [T(n) - T(n-1)] \quad (1)$$

343 Where C_T denotes the corrected actual conductivity at the n -th
344 sampling instant (corresponding to the temperature sensor location), $T(n)$
345 is the measured temperature, and γ is the sensitivity coefficient of
346 conductivity to temperature. The coefficients a and b are determined by
347 the following equations:

$$348 \quad a = 4f_n \cdot \alpha \tau (1 + 4f_n \cdot \alpha \tau)^{-1}, b = 1 - 2a\alpha^{-1} \quad (2)$$

349 Where f_n is the Nyquist frequency, a is the dimensionless
350 correction amplitude, and τ is the time constant (in seconds). The
351 parameters α and τ are critical determinants of correction accuracy, and
352 their values typically depend on the velocity of seawater flowing through
353 the conductivity cell. Given that the flow velocity for UGs and AUVs
354 varies dynamically during diving and ascending phases, this study employs
355 a variable-flow coefficient method, modeling α and τ as functions of
356 the flow velocity V :



357
$$\alpha(n) = \alpha_o + \alpha_s V(n)^{-1}, \tau(n) = \tau_o + \tau_s V_f(n)^{-0.5} \quad (3)$$

358 Where $V(n)$ represents the average flow velocity of seawater
359 through the conductivity cell at the n -th instant (m/s); the subscripts O
360 and S denote the offset and slope, respectively; and $\alpha_o, \alpha_s, \tau_o, \tau_s$ are the
361 characteristic parameters to be fitted.

362 In the data processing workflow of this study, we first adopted the
363 SQP optimization framework proposed by Garau et al. (2011). Assuming
364 that the properties of the water mass remain constant during a single profile
365 ascent and descent, we iteratively solved for the characteristic parameters
366 by minimizing the difference in area between the ascent and descent T-S
367 curves. After completing this preliminary thermal lag correction and
368 calculating salinity over the standard atmospheric pressure layer, we
369 incorporated the improved strategy proposed by Liu et al. (2015) to further
370 eliminate residual salinity jump noise caused by sensor response
371 mismatches. Specifically, we applied median filtering to the corrected
372 temperature, conductivity, and salinity time series to ensure the reliability
373 and smoothness of the final dataset.

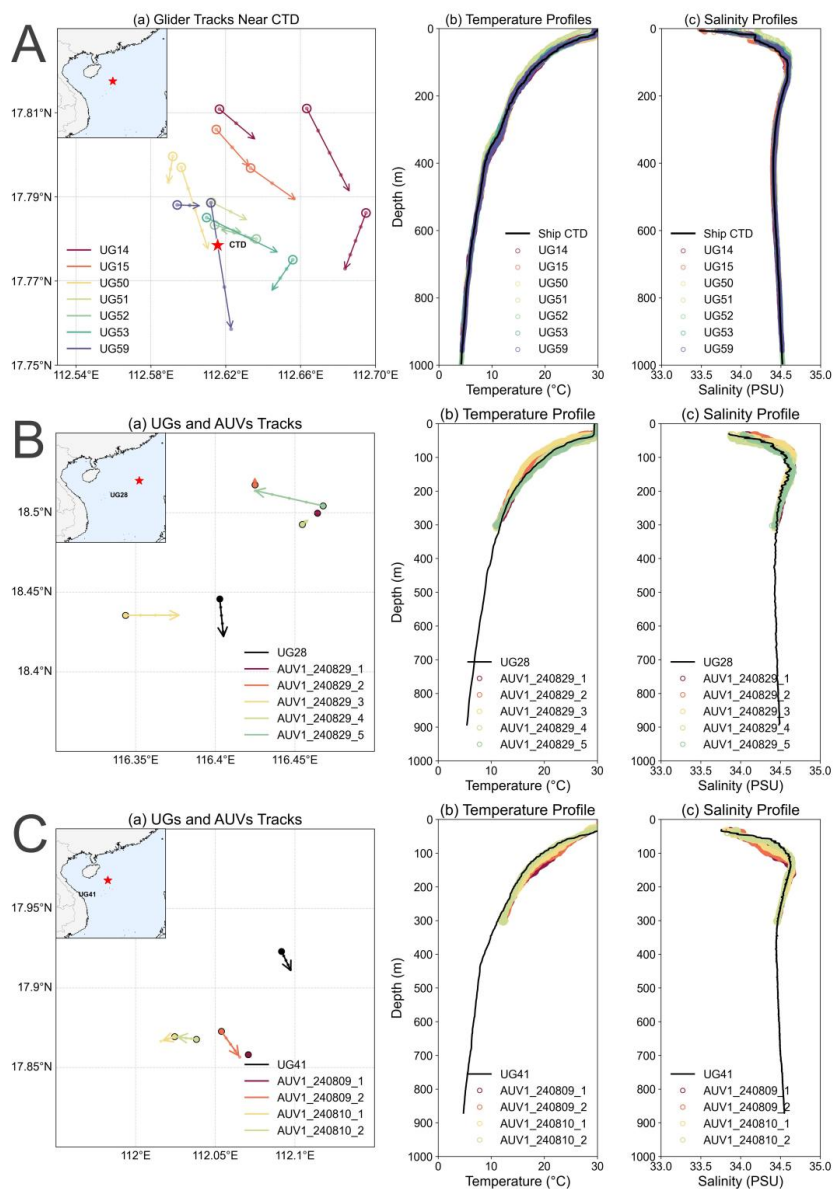
374 3.3 Cross-validation results

375 To assess the reliability of the data, the temperature and salinity
376 profiles observed by the UG were cross-validated against ship-based CTD
377 measurements collected in July 2024 (Fig. 4A(a)-4A(c)). These CTD
378 profile data were obtained using the SBE 911plus CTD instrument, which



379 collects data at a high frequency of 24 Hz and has an operational range
380 exceeding 1,000 m in depth, which exceeds the maximum operational
381 depth of the gliders. Prior to deployment, the SBE 911plus CTD sensors
382 underwent a rigorous standard calibration process to ensure the reliability
383 of the observational data. Given the sparse distribution of AUV observation
384 stations (Fig. 1) and the significant spatial gaps between AUV tracks and
385 ship-based CTD deployment points, a direct comparison was not feasible.
386 Therefore, spatially and temporally adjacent UG profiles were used as a
387 reference benchmark to indirectly validate the AUV temperature and
388 salinity profiles (Fig. 4B(a)-4B(c), 4C(a)-4C(c)).

389 Quantitative analysis revealed a mean bias of 0.03°C for temperature
390 and 0.01 psu for salinity. Cross-validation among the ship-based CTD, UG,
391 and AUV datasets indicated a high degree of consistency in the vertical
392 hydrographic structure, thereby strongly confirming the reliability and
393 accuracy of the multi-platform observational data used in this study.



394

395 Figure 4. Cross-validation of co-located observations from shipboard, UG-mounted,
 396 and AUV-based CTDs, focusing on: A(a)-C(a) spatial correspondence, A(b)-C(b)
 397 temperature, and A(c)-C(c) salinity. The black lines in A(b)-A(c) represent ship-based
 398 measurements, while the black lines in B(b)-B(c) and C(b)-C(c) represent UG
 399 measurements. The colored circles represent different missions of the UG or AUV,
 400 respectively.



401 4 The typhoon events observed by UG and AUV

402 4.1 Vertical variations in temperature and salinity sections observed by
403 UGs and AUVs

404 Typhoons induce intense disturbances in the ocean surface layer
405 through strong wind stresses, typically leading to a series of changes in the
406 temperature, salinity, and depth of the mixed layer. By sailing along paths
407 near typhoon tracks, a three-dimensional observation network comprising
408 UG arrays and AUVs recorded hundreds of vertical temperature-salinity
409 profiles driven by seven typhoons. Fig. 5 illustrates the thermohaline
410 changes during the passage of three typhoons: MALIKSI (No. 2402),
411 SOULIK (No. 2415), and MAN-YI (No. 2424).

412 Typically, typhoons induce significant sea surface cooling and salinity
413 increase through intense vertical mixing driven by wind stress, Ekman
414 pumping, and heat and freshwater flux exchanges between the ocean and
415 atmosphere. These processes trigger the upwelling of deep cold water and
416 the entrainment of high-salinity subsurface water, while the input of large
417 amounts of turbulent kinetic energy disrupts stratification, leading to a
418 deepening of the mixed layer. During the passage of Typhoon MAN-YI
419 (No. 2424), distinct signals of sea surface cooling and salinity increase
420 were observed in the temperature-salinity profiles (indicated by the red
421 dashed boxes in Fig. 5C(b) and (c)). Further statistical analysis of the
422 temperature-salinity profiles revealed that Typhoons YAGI (No. 2411),



423 TRAMI (No. 2420), YINXING (No. 2422), and MAN-YI (No. 2424) had
424 particularly significant cooling effects on the sea surface. Within the top 40
425 meters, temperatures decreased by 1–4°C, and salinity increased by 0.1–
426 0.5 psu. Additionally, these four typhoons triggered intense vertical mixing,
427 resulting in varying degrees of deepening of the mixing layer. Notably,
428 following the passage of Typhoon YAGI (No. 2411), the mixing layer depth
429 extended to approximately 80 m. In contrast, due to the observation points
430 distance from the storm center, no significant changes in the vertical
431 temperature-salinity structure were observed during the passage of
432 Typhoon PRAPIROON (No. 2404).

433 The observation network also revealed distinctly different vertical
434 thermohaline evolution processes during the passages of Typhoons
435 MALIKSI and SOULIK. For Typhoon MALIKSI (No. 2402), although
436 temperature section data recorded a brief cooling of the sea surface during
437 the event, this was followed by significant surface warming and a sharp
438 drop in salinity (indicated by the red dashed boxes in Fig. 5A(b) and (c)).
439 A combined analysis of vorticity and precipitation (Appendix A Fig. A1)
440 indicates that a strong “precipitation-radiation” coupling effect overrode
441 the conventional wind-driven mixing cooling mechanism. Intense typhoon
442 rainfall formed a thick, low-salinity freshwater cap at the surface (with
443 cumulative precipitation reaching 136 mm within 24 hours after 12:00 on
444 May 30), significantly enhancing density stratification and creating a

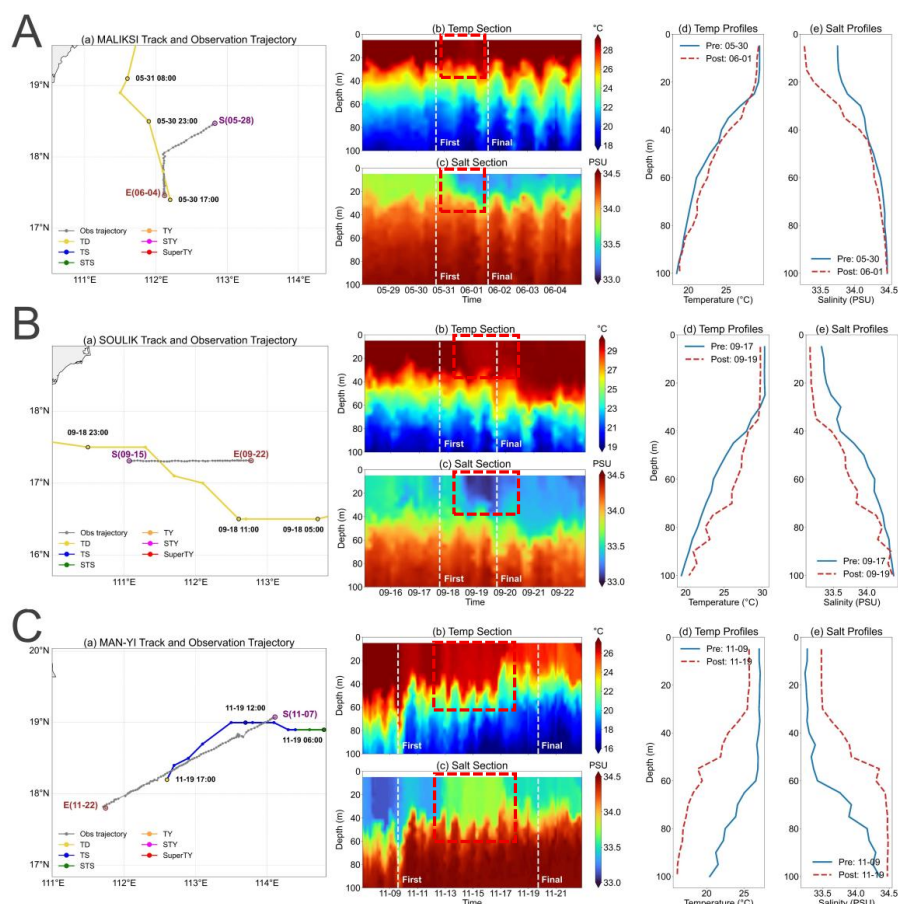


445 barrier layer that effectively suppressed the upwelling and entrainment of
446 deep cold water. Subsequently, high-intensity seasonal shortwave solar
447 radiation rapidly heated this layer, leading to heat accumulation rather than
448 downward diffusion, and ultimately resulting in a surface warming and
449 precipitation-dominated salinity anomaly. In contrast, Typhoon SOULIK
450 (No. 2415) exhibited more complex dynamical processes as it passed over
451 the observation site (indicated by the red dashed boxes in Fig. 5B(b) and
452 (c)). Although a typical sea-surface cooling event occurred on Sept. 19,
453 salinity exhibited a non-monotonic “first-decrease-then-increase” pattern
454 inconsistent with a simple cold-water upwelling mechanism. Observation
455 trajectory and eddy field analysis confirmed that UG entered a background
456 warm eddy between Sept. 19 and 22 (Appendix A Fig. A2). The nonlinear
457 interaction between typhoon-induced vertical mixing and the warm eddy’s
458 inherent high-temperature, low-salinity characteristics led to the observed
459 simultaneous initial decrease in temperature and salinity, which
460 subsequently shifted to a cooling and salinity-increasing process due to
461 cold water upwelling. This highlights the key moderating role of
462 background mesoscale vortices in typhoon-induced oceanic responses.

463 In summary, the collaborative observation network comprising the
464 UG array and AUVs demonstrated exceptional capability in capturing the
465 complex oceanic responses triggered by typhoons. In addition to clearly
466 documenting typical wind-driven mixing, cooling, and salinity increase



467 processes, the system, leveraging its high spatiotemporal resolution,
468 successfully captured fine-scale vertical structural changes that differ
469 markedly from traditional wind-driven mixing mechanisms. These changes
470 specifically include the rapid surface warming and salinity dilution
471 triggered by Typhoon MALIKSI (No. 2402), as well as the complex
472 temperature-salinity signals resulting from the nonlinear interaction
473 between Typhoon SOULIK (No. 2415) and the background warm eddy.
474 These observational results conclusively demonstrate that the UG-AUV
475 joint observation system can accurately resolve three-dimensional
476 temperature and salinity evolution regulated by multiple physical
477 mechanisms under extreme weather conditions, providing critical data
478 support for elucidating the underlying dynamics of typhoon-ocean
479 interactions.



480

481 Figure 5. Typhoon-induced changes in the vertical structure of temperature and salinity
 482 (A-C show observations during Typhoons MALIKSI, SOULIK, and MAN-YI,
 483 respectively). A(a)-C(a) illustrates the relative spatial positions of the typhoon tracks
 484 and the observation platforms, while A(b)-C(b) and A(c)-C(c) show the temperature
 485 and salinity sections, and A(d)-C(d) and A(e)-C(e) show their profiles within the upper
 486 100 m, respectively. The red dashed boxes in A(b) and A(c) show the cooling and
 487 salinity-decreasing process caused by precipitation; the red dashed boxes in A(b) and
 488 A(c) show the cooling and salinity-decreasing process caused by a background warm
 489 eddy; and the red dashed boxes in A(b) and A(c) show the cooling and salinity-
 490 increasing process caused by upwelling and vertical mixing.

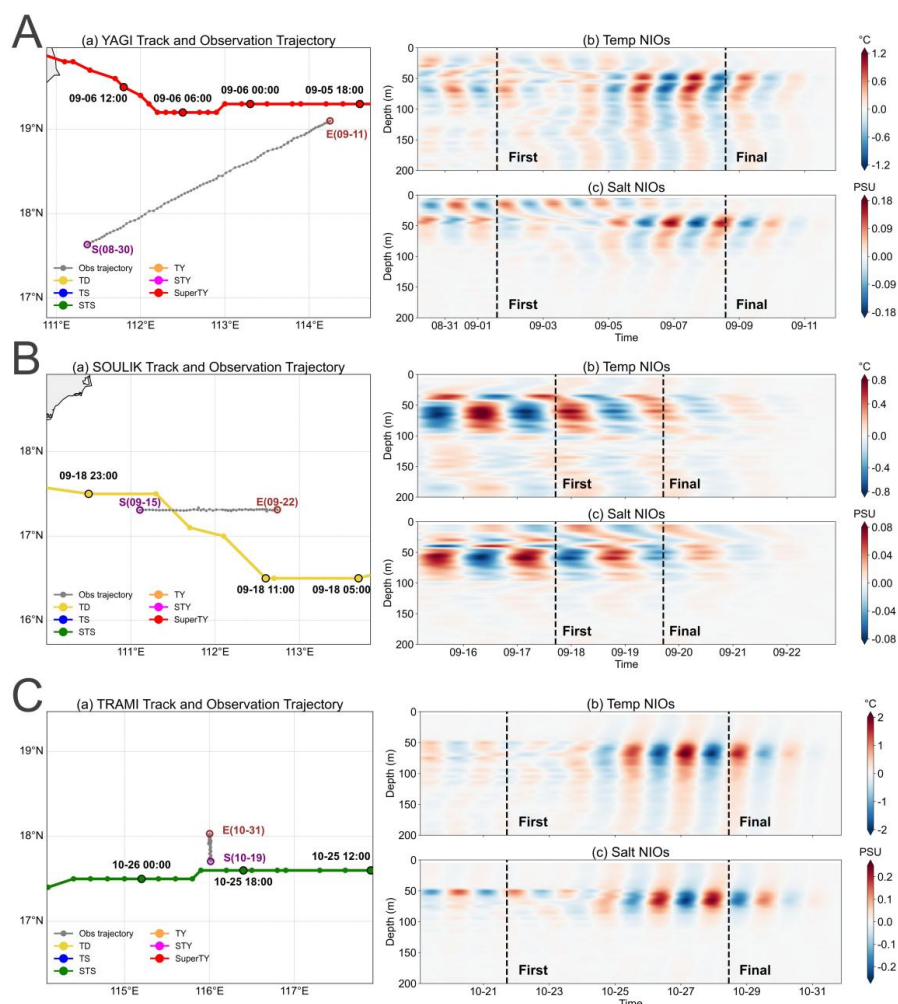
491 4.2 Thermohaline NIOs observed by UGs and AUVs



492 In addition to significant thermohaline thermodynamic changes, the
493 response of the upper ocean to typhoons is also manifested dynamically in
494 the form of NIOs. During the mission, UGs and AUVs deployed around
495 the typhoon tracks extensively observed typhoon-induced periodic
496 temperature and salinity oscillations. Taking Typhoons YAGI (No. 2411),
497 SOULIK (No. 2415), and TRAMI (No. 2420) as examples, the average
498 latitude of the observation points during the typhoon transit was used as
499 the reference latitude for calculating the local inertial frequency. The
500 inertial frequency is calculated using the following formula:

$$501 \quad f = 2\Omega \sin \phi \quad (4)$$

502 where f is the local inertial frequency, Ω is the Earth's rotation rate (a
503 constant), and ϕ is the local latitude. Based on the local inertial frequency,
504 a fourth-order Butterworth filter was applied to extract the NIO
505 components of temperature and salinity from the section data, using a
506 filtering frequency band of $[0.8, 1.2] f$.



507
 508 Figure 6. Observations of NIOs during Typhoons (A) YAGI, (B) SOULIK, and (C)
 509 TRAMI. Panels (a) depict typhoon tracks and observational trajectories; (b)
 510 temperature NIOs; and (c) salinity NIOs. In panel (a), colored lines indicate typhoon
 511 tracks with intensity information, where specific points highlighted by black outlines
 512 denote the time of passage. Gray lines represent the trajectories of the UG or AUV, with
 513 the start (purple circle, labeled “S(month–date)”) and end (brown circle, labeled
 514 “E(month–date)”) points emphasized. In panels (b) and (c), vertical black dashed lines
 515 mark the times of the first and final typhoon warnings, labeled “First” and “Final,”
 516 respectively.



517 Observational results from systems deployed in the vicinity of the
518 typhoon-affected regions of YAGI, SOULIK, and TRAMI indicate that
519 significant periodic variations in the upper-ocean temperature and salinity
520 structure occurred after the passage of the typhoons. As shown in the series
521 of panels in Fig. 6(b) and (c), temperature-induced NIOs were primarily
522 confined to the upper 200 m of the water column, whereas salinity NIOs
523 exhibited a notably shallower influence depth, mainly concentrated within
524 the upper 100 m. In this study, the 75 m depth layer was selected, where
525 NIOs signals were particularly strong, to compute the power spectral
526 density and oscillation periods of temperature and salinity NIOs (Appendix
527 A Fig. A3). The results show that the observed NIO oscillation periods
528 closely match the local inertial period. Specifically, the NIO frequency
529 derived from Typhoon TRAMI (0.0260 cph) deviates by only 1% from the
530 local inertial frequency (0.0257 cph), and the calculated oscillation period
531 (38.5 h) differs from the inertial period (38.9 h) by merely 0.4 h.

532 Statistical analysis of NIOs data of 7 typhoons reveals that the mean
533 period of temperature NIOs is 39.08 ± 3.86 h, while that of salinity NIOs
534 is 38.54 ± 3.52 h. Both are clustered around 39 h, which is consistent with
535 the theoretical inertial period (~ 39 h) at the observational network's
536 operational latitude ($\sim 18^\circ\text{N}$). The mean amplitude of temperature NIOs is
537 2.0°C , and that of salinity NIOs is 0.16 PSU, both falling within the typical
538 range for near-inertial oscillations in temperature and salinity. The high



539 degree of consistency between the oscillation periods of temperature and
540 salinity NIOs indicates that they reflect the same underlying physical
541 process—namely, typhoon-induced near-inertial oscillations in the upper
542 ocean.

543 In summary, the UG and AUV systems deployed during this
544 observational campaign successfully captured temperature and salinity
545 NIO signals in the upper ocean following typhoon passage, owing to their
546 capability for large-scale, high-precision, and continuous monitoring.
547 These instruments clearly revealed the vertical distribution, oscillation
548 periods, and amplitude characteristics of NIOs, thereby demonstrating their
549 effectiveness and reliability in observing oceanic dynamical responses to
550 typhoons. This study provides high-quality observational data to support
551 further research into the mechanisms of typhoon-upper ocean interactions.

552 5 Data availability

553 The paired data for Typhoon-UGs/AUVs have been made publi
554 cly available along with this paper and can be accessed on Zenodo
555 via <https://doi.org/10.5281/zenodo.19656867> (Qi et al., 2026). The ty
556 phoon best-track data (IBTrACS) were obtained from <https://www.nc>
557 [ei.noaa.gov/products/international-best-track-archive](https://www.nc.ei.noaa.gov/products/international-best-track-archive). CMEMS Level-4
558 SLA data were obtained from <https://data.marine.copernicus.eu>. ERA
559 5 precipitation and evaporation data were obtained from <https://cds.c>
560 [limat.copernicus.eu/datasets](https://cds.climat.copernicus.eu/datasets).



561 6 Conclusions and outlook

562 Based on a six-month joint observation campaign involving both UGs
563 and AUVs, this study has constructed a high-resolution, long-term dataset
564 of ocean temperature and salinity profiles under typhoon conditions. This
565 comprehensive dataset comprises 4459 profiles and covers seven typhoon
566 events. A total of 62 UGs and 2 AUVs were deployed, yielding 112 sets of
567 valid paired samples of typhoon event data and observations from
568 UGs/AUVs. As the first long-term temperature and salinity dataset
569 equipped with active observation devices, this study captures the evolution
570 of typhoon-driven vertical structures of upper ocean temperature and
571 salinity, as well as near-inertial oscillation signals. This dataset provides an
572 observational foundation for studying the response processes of the upper
573 ocean under typhoon forcing and reveals the complex nonlinear interaction
574 mechanisms among wind-driven mixing, precipitation input, and
575 background eddies. However, quantitative studies on the transfer of
576 typhoon energy to the ocean and its transmission efficiency still require
577 longer-term, more intensive observation data from UG and AUV.

578 In addition to moored buoys, we are pleased to note that UGs and
579 AUVs have proven capable of capturing NIOs events, revealing the
580 vertical structural characteristics of stratification changes. Although UG
581 and AUV demonstrate unique advantages in capturing NIOs, their
582 sampling methods still have certain limitations. Due to the use of zigzag

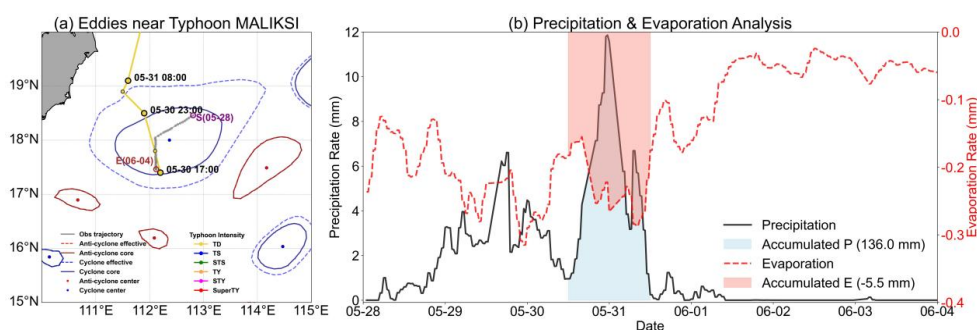


583 trajectories for spatial scanning, their horizontal movement speed is far
584 lower than the phase velocity of near-inertial waves, making them prone to
585 spatiotemporal aliasing effects when reconstructing the horizontal velocity
586 field. This spatial aliasing caused by the sampling trajectories may distort
587 high-frequency velocity signals, leading to a systematic underestimation of
588 near-inertial kinetic energy. Future plans include cross-validating and time-
589 constraining data using moored buoys or performing multi-profile phase
590 correction using repeated observations.

591 The main challenges encountered during observations include: (1)
592 partial data loss under extreme sea conditions; (2) some equipment failed
593 to effectively cover the target area due to the route deviating from the
594 typhoon's forced core region. Future optimizations can be made in the
595 following areas: (1) improving the buoyancy control system, enhancing the
596 wind and wave resistance of the equipment housing, and establishing a
597 real-time data quality monitoring and anomaly handling mechanism; (2)
598 prioritizing high-frequency sampling in the typhoon's near-field and forced
599 core region, while dynamically adjusting the observation route based on
600 typhoon track forecasts to capture rapid response processes in the upper
601 ocean. Resolving these issues will require continued collaboration among
602 the field operations team, platform engineers, and dynamical
603 oceanographers to drive further optimization of the autonomous sampling
604 system.

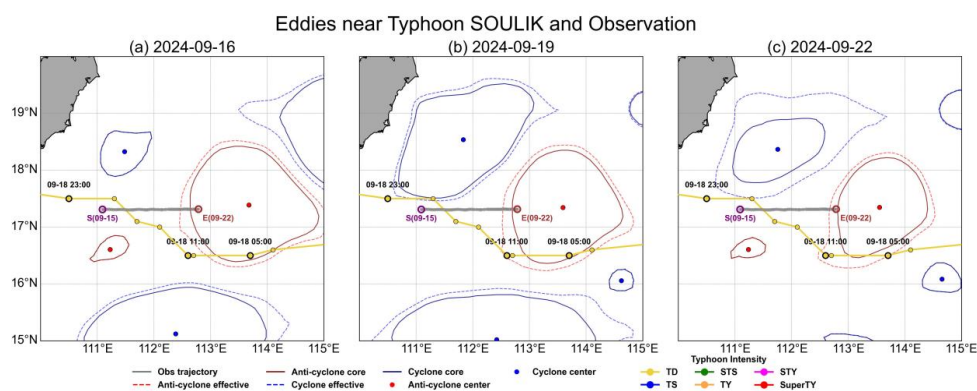


605 Appendix A



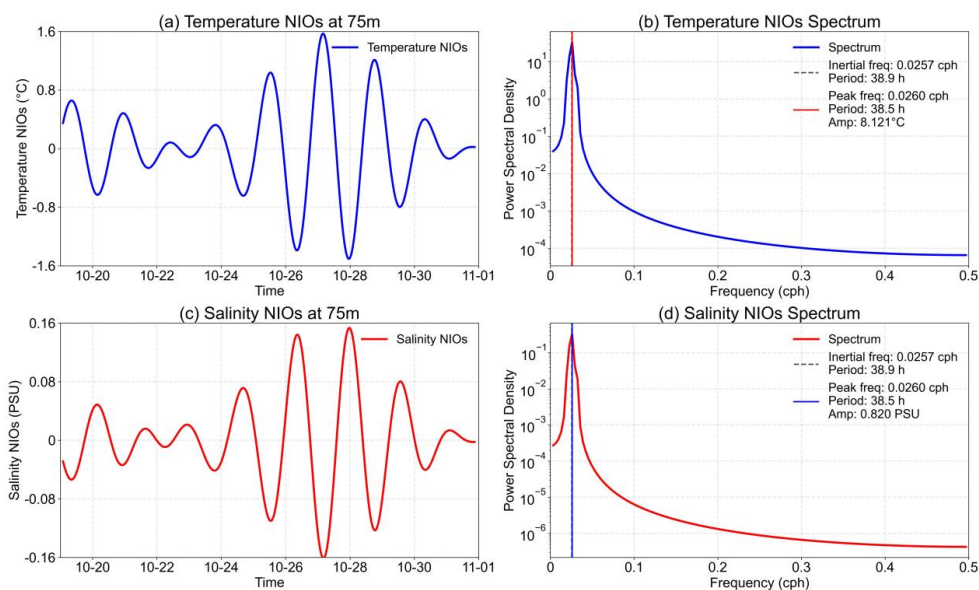
606

607 Figure A1. (a) Eddy distribution on May 31 and (b) precipitation and evaporation along
 608 the UG track during Typhoon MALIKSI (No. 2402). (a) shows that during MALIKSI
 609 passage, the UG track remained within a background cold eddy, which exhibited “low
 610 temperature and high salinity” characteristics. (b) shows that from May 30 to May 31
 611 (when the UG was closest to the typhoon track), the 24 h cumulative precipitation and
 612 evaporation were 136 mm (reaching the level of a torrential rain event) and -5.5 mm,
 613 respectively. This resulted in a net freshwater flux of 141.5 mm, constituting an extreme
 614 precipitation event that would form a significant “freshwater cap” at the ocean surface,
 615 leading to a decrease in surface seawater salinity.



616

617 Figure A2 Distribution of eddies during Typhoon SOULIK (No. 2415) on (a) Sept. 16,
 618 (b) Sept. 19, and (c) Sept. 22, 2024. During this period, UG entered a background warm
 619 eddy. Its “high-temperature, low-salinity” characteristics caused a decrease in salinity
 620 in the temperature-salinity section, forming a nonlinear interaction process of “cooling
 621 and desalination” with the typhoon-induced cooling (Fig. 5B(b) and (c)).



622

623 Figure A3. (a) Temperature NIOs and (b) salinity NIOs observed at a depth of 75 m
624 during Typhoon TRAMI (No. 2420), along with (c) the power spectrum of the
625 temperature NIOs and (d) the power spectrum of the salinity NIOs. The NIOs frequency
626 calculated from the power spectra (0.0260 cph) deviates from the local inertial
627 frequency (0.0257 cph) by only 1%, and the calculated oscillation period (38.5 h)
628 deviates from the inertial period (38.9 h) by only 0.4 h, indicating that the NIOs
629 oscillation period captured by the observation system is in excellent agreement with the
630 local inertial period.

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632 Conceptualization: Lei Liu, Jianfang Fei. Data curation: Jiawei Qi,
633 Wenhui Liu. Investigation: Jiancheng Yu, Zhiduo Tan, Huabin Mao. Project
634 administration: Zhanhong Ma, Xiaogang Huang, Xiaoping Cheng. Writing:
635 Jiawei Qi, Lei Liu. All the authors have read and agreed to the published
636 version of the paper.

637 Competing interests



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

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