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1 **Comparison of two-dimensional Flood Propagation Models: SRH-** 2 **2D and Hydro_AS-2D**

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11 **Abstract**

12 This article presents a comparison between two two-dimensional finite volume flood
13 propagation models: SRH-2D and Hydro_AS-2D. The models are compared using an
14 experimental dam-break test-case provided by Soares-Frazão (2007). Four progressively refined
15 meshes are used, and both models react adequately to mesh and time step refinement.
16 Hydro_AS-2D shows some unphysical oscillations with the finest mesh and a certain loss of
17 accuracy. For that test-case, Hydro_AS-2D is more accurate for all meshes and generally faster
18 than SRH-2D. Hydro_AS-2D reacts well to automatic calibration with PEST, whereas SRH-2D has
19 some difficulties in retrieving the suggested Manning's roughness coefficient.

20 **Author Keywords:** Model comparison; Two-dimensional flow modeling; Hydro_AS-2D;

21 SRH-2D; Automatic calibration

22 **Notations**

23	D	Hydraulic diameter
24	e	Source term
25	g	Gravitational acceleration
26	h	Water depth
27	k	Turbulent kinetic energy
28	n	Manning's roughness coefficient
29	S_{fx}, S_{fy}	Energy slope
30	S_{bx}, S_{by}	Bed slope
31	T	Turbulence stress
32	u, v	Velocity components
33	z	Water surface elevation
34	z_b	Bed elevation
35	μ	Eddy viscosity
36	μ_0	Kinematic viscosity of water
37	μ_t	Turbulent eddy viscosity
38	ρ	Mass density
39	τ	Shear stress

40 **1 Introduction**

41 Flood propagation may induce important human and material losses and remains a major
42 challenge for hydraulic engineers due to the complexity of the phenomenon and therefore to
43 the difficulties that arise in their numerical modeling. Two-dimensional models are now widely
44 used in flood propagation modeling owing to the gain in precision they offer and their relatively
45 small time consumption. Different types of methods were used for the numerical modeling of
46 shallow water equations as finite differences, finite elements and finite volumes. For fluid flows,
47 the last is currently accepted as the most accurate and has been implemented in several models
48 such as TUFLOW-FV (BMTWBM 2014), RiverFlow2D (Hydronia 2015), SRH-2D (Lai 2008),
49 Hydro_AS-2D (Nujic 2003), HEC-RAS (Brunner 2016) and BASEMENT (Vetsch 2015). If these
50 models are usually validated by their designer, few model-to-model comparisons exist. It is yet
51 of great importance for practicing engineers to have objective and precise comparisons on
52 which they can rely for the choice of a flood propagation model. The aim of this paper is to
53 provide such a comparison for two models: Hydro_AS-2D, which is mainly used in European
54 countries, and SRH-2D, largely used in North America.

55 SRH-2D was validated against numerous experimental, analytical and river cases. Lai (2008) and
56 Lai (2010) showed that the model reacts correctly compared with the analytical solution of a
57 transcritical flow with a hydraulic jump in a 1D channel that was proposed by MacDonald (1996).
58 SRH-2D was also used to model the 2D diversion flow case measured by Shettar et Murthy
59 (1996) with the conclusion that the flow was better modeled along the walls by SRH-2D with the
60 k-epsilon turbulence model than with the parabolic model (Lai 2008; Lai 2010). Experimental
61 data of a channel with bend proposed by Zarrati et al. (2005) were modeled with SRH-2D and
62 showed that the computed water depth was less sensitive to mesh resolution than the velocity
63 (Lai 2008; Lai 2010). The model was used to evaluate the impact of a dam removal on the Sandy
64 River Delta with satisfactory results. A similar study was undertaken for the Savage Rapids dam
65 removal and achieved good results in modeling the water depth and hydraulic jump (Lai 2008;
66 Lai 2010).

67 Jones (2011) made a comparison of four two-dimensional hydrodynamic models: ADH (Berger et
68 al. 2013), FESWMS (Froehlich 2002), RMA2 (Donnell 2006) and Hydro_AS-2D (Nujic 2003).
69 Applied to three test-cases, Hydro_AS-2D proved to be the most stable and easy to use and was
70 able to run in some cases where other models could not. Hydro_AS_2D was also the fastest
71 model.

72 Tolossa (2008) and Tolossa et al. (2009) compared the two-dimensional hydrodynamic models
73 Hydro_AS-2D and SRH-W, which was the first released version of SRH-2D. The models were
74 compared on three river reaches and were able to appropriately recreate the water depth. The
75 authors report that SRH-W seems more sensitive to mesh refinement, meaning that a finer
76 mesh was needed to reach a precision comparable to Hydro_AS-2D. SRH-W was the fastest
77 model of this study.

78 Both models have been tested in numerous studies and have been proven to be reliable.
79 However, the previous comparisons and test-cases did not state which of SRH-2D and
80 Hydro_AS-2D could best predict the water depth. It is therefore the purpose of this paper to
81 provide a clear statement on which model is best for forecasting flow parameters. The
82 computation time will be compared as well to confirm or nuance previous studies. In addition, a
83 new feature, which has, to the best of our knowledge, never been used to compare
84 hydrodynamic models, is studied for the purpose of this comparison: automatic calibration.
85 Automatic calibration is becoming increasingly used in hydrodynamic and hydrologic modeling
86 (Ellis et al. 2009; Fabio et al. 2010; McCloskey et al. 2011; McKibbin et Mahdi 2010) because it
87 provides important gains not only in the calibration's necessary time but also in the calibrated
88 parameters' values. Thus, it is important to ensure that models react correctly to an automatic
89 calibration.

90 **2 Presentation of Models**

91 **2.1 SRH-2D Version 3**

92 SRH-2D solves the shallow water equations using the following form (Lai 2008; Lai 2010):

$$93 \quad \frac{\partial h}{\partial t} + \frac{\partial hu}{\partial x} + \frac{\partial hv}{\partial y} = e \quad (\text{Eq. 1})$$

$$94 \quad \frac{\partial hu}{\partial t} + \frac{\partial huu}{\partial x} + \frac{\partial huv}{\partial y} = \frac{\partial hT_{xx}}{\partial x} + \frac{\partial hT_{xy}}{\partial y} - gh \frac{\partial z}{\partial x} - \frac{\tau_{bx}}{\rho} \quad (\text{Eq. 2})$$

$$95 \quad \frac{\partial hv}{\partial t} + \frac{\partial huv}{\partial x} + \frac{\partial hvv}{\partial y} = \frac{\partial hT_{xy}}{\partial x} + \frac{\partial hT_{yy}}{\partial y} - gh \frac{\partial z}{\partial y} - \frac{\tau_{by}}{\rho} \quad (\text{Eq.3})$$

96 The friction is determined using the Manning equation:

97
$$\begin{pmatrix} \tau_{bx} \\ \tau_{by} \end{pmatrix} = \rho C_f \begin{pmatrix} u \\ v \end{pmatrix} \sqrt{u^2 + v^2} \quad C_f = \frac{gn^2}{h^{1/3}} \quad (\text{Eqs. 4 and 5})$$

98 Boussinesq equations are used to compute the turbulence stresses:

99
$$T_{xx} = 2(\mu_0 + \mu_t) \frac{\partial u}{\partial x} - \frac{2}{3}k \quad (\text{Eq. 6})$$

100
$$T_{xy} = (\mu_0 + \mu_t) \left(\frac{\partial u}{\partial y} + \frac{\partial v}{\partial x} \right) \quad (\text{Eq. 7})$$

101
$$T_{yy} = 2(\mu_0 + \mu_t) \frac{\partial v}{\partial y} - \frac{2}{3}k \quad (\text{Eq. 8})$$

102 where h is the water depth, u and v are the velocity components, z is the water surface
 103 elevation, e is a source term, T are the turbulent stresses, τ is the shear stress, g is the
 104 gravitational acceleration, ρ is the mass density, μ_0 is the kinematic viscosity of water, μ_t is the
 105 turbulent eddy viscosity, k is the turbulent kinetic energy, and n is Manning's roughness
 106 coefficient.

107 SRH-2D proposes two turbulence models: k -epsilon and depth-averaged parabolic models. The
 108 parabolic model is used in the present study because it is the only turbulence model used by
 109 Hydro_AS-2D, and a proper comparison necessitates identical parameters. SRH-2D uses a
 110 wetting–drying front limit of 0.001 m. Below this value, water depth is considered to be equal to
 111 0 m on the cell, and SRH-2D does not solve the shallow water equations (Lai 2010).

112 **2.2 Hydro_AS-2D Version 4**

113 Shallow water equations, as solved by Hydro_AS-2D, are expressed in vectors (Nujic 2003):

114
$$\frac{\partial w}{\partial t} + \frac{\partial f}{\partial x} + \frac{\partial g}{\partial y} + S = 0 \quad (\text{Eq. 9})$$

115
$$w = \begin{bmatrix} z \\ uh \\ vh \end{bmatrix} \quad f = \begin{bmatrix} uh \\ u^2h + 0.5gh^2 + \mu h \frac{\partial u}{\partial x} \\ uvh - \mu h \frac{\partial v}{\partial x} \end{bmatrix} \quad (\text{Eq. 10})$$

116
$$g = \begin{bmatrix} vh \\ uvh - \mu h \frac{\partial u}{\partial y} \\ v^2h + 0.5gh^2 + \mu h \frac{\partial v}{\partial y} \end{bmatrix} \quad S = \begin{bmatrix} 0 \\ gh(S_{fx} - S_{bx}) \\ gh(S_{fy} - S_{by}) \end{bmatrix} \quad (\text{Eq. 11})$$

117 The bed slope is defined as follows:

118
$$S_{bx} = -\frac{\partial z_b}{\partial x} \quad S_{by} = -\frac{\partial z_b}{\partial y} \quad (\text{Eqs. 12 and 13})$$

119 The energy slope is computed following the Darcy–Weisbach equation, and the friction
120 coefficient is determined with the Manning formula:

121
$$S_f = \left(6.34 \frac{2gn^2}{D^{1/3}} \right) \cdot \left(\frac{v|v|}{2gD} \right) \quad (\text{Eq. 14})$$

122 where μ represents the eddy viscosity, S_f is the energy slope, z_b is the bed elevation, and D is the
123 hydraulic diameter.

124 The default wetting–drying front limit is set to 0.01 m but is lowered to 0.001 m for the current
125 study. Time steps are calculated automatically and continuously by Hydro_AS-2D over the
126 modeling.

127 **2.3 SMS Version 12.1**

128 The Surface–water Modeling System, SMS (AQUAVEO 2016), facilitates the required
129 pretreatment and post-treatment for hydraulic modeling of open channel flow. SMS includes
130 many characteristics of GIS software and uses them, for example, in the creation of quality
131 meshes. The results may be viewed in three dimensions, and many tools are available for their

132 treatment, which makes SMS very versatile and usable with multiple models (AQUAVEO 2016).
133 For the present study, SMS allows with great ease the use of the same mesh and boundary
134 conditions for the two models, SRH-2D and Hydro_AS-2D, which is necessary for a proper
135 comparison.

136 **2.4 PEST Version 13**

137 PEST (Doherty 2005) is a software program that executes the automatic calibration and
138 sensibility analysis of any model based on input and output files. In this study, only the
139 automatic calibration module is used. Automatic calibration with PEST requires three main types
140 of files: template, instruction and control files (figure 1).

- 141 ○ Template files act as models for PEST when creating input files to calibrate the model
142 (i.e., SRH-2D and Hydro_AS-2D).
- 143 ○ Instruction files aid PEST in the interpretation of the model's output by indicating the
144 values that should be used for the calibration.
- 145 ○ The control file contains calibration instructions, such as stopping criteria and observed
146 values. It relates the template and instruction files to the model's files to which they
147 refer.

148 PEST is therefore model independent and relatively simple to use, which makes it a powerful
149 tool for the calibration of two-dimensional hydrodynamic models.

150 **3 Methodology**

151 The comparison of SRH-2D and Hydro_AS-2D is made on experimental data and aims to verify
152 the accuracy of both models, their sensitivity to spatial and time discretization, and their
153 response to automatic calibration.

154 **3.1 Test-case**

155 The two models are compared using an experimental dataset presented by Soares-Frazão (2007)
156 in which a dam break wave over a triangular bottom sill is studied. The rectangular channel has
157 a width of 0.5 m and a length of 5.6 m, and the sill height is 0.065 m with a symmetrical slope of
158 approximately 14% (figure 2). The suggested Manning's roughness coefficient is $0.011 \text{ s/m}^{1/3}$.
159 The initial conditions (figure 2) are made of an upstream reservoir in which the water depth is
160 0.111 m and by a downstream pool, isolated from the rest of the channel by the sill, with a
161 water depth of 0.02 m. The central section is initially dry. The reservoir is isolated by a gate
162 whose sudden removal creates the propagation of the dam-break wave upon the channel.

163 All four boundaries of the channel consist of walls, meaning that the wave will successively
164 reflect against the downstream and upstream walls. The wave first propagates on the dry bed to
165 reach the sill where the water is partly reflected to the upstream part of the channel and partly
166 continues to reach the water pool located downstream of the sill. Reflections are then
167 simultaneously observed in the sections of the channel located on both sides of the sill.

168 Three gauges are positioned around the triangular sill to monitor the incidence of this feature
169 on the flow. The monitoring lasts 45 s, during which the water depths are available every 0.01 s,
170 for a total of 4501 measurements for each gauge.

171 **3.2 Time Step and Mesh Sensitivity and Water Depth Accuracy**

172 The simulation is made with SRH-2D on four progressively refined meshes (figure 3) that are all
173 modeled with five time steps (tables 1 and 2). These twenty simulations are then used to
174 investigate the sensitivity of SRH-2D to these parameters and will ensure that a mesh and time
175 step independent solution is achieved. The time step providing the best results is afterward
176 used for the comparison with Hydro_AS-2D. Hydro_AS-2D computes the time step required to

177 fulfill the Courant condition, so the user does not have influence on that parameter. Therefore,
178 only the mesh sensitivity is evaluated for this model. The meshes used are the same as those
179 presented above for SRH-2D.

180 The comparison is then made on the four meshes, and the quality of the simulations is
181 quantified through the calculation of the root mean squared error (RMSE) considering the
182 calculated and measured water depth every 0.1 s for a total of 450 benchmark measurements
183 by gauge.

184 All simulations last 45 s, and the depth-averaged parabolic model is used for turbulence for both
185 SRH-2D and Hydro_AS-2D. The minimum water depth for the treatment of the wetting and
186 drying front is 0.001 m, and the maximum velocity is 15 m/s for Hydro_AS-2D. The wetting and
187 drying front limit is also 0.001 m for SRH-2D, but the maximum velocity is unknown. All wall
188 boundaries are assigned a no-slip condition. All calculations are made with a 64 GB server with
189 an Intel Xeon CPU E5-2630 v3 @2.40 GHz processor.

190 **3.3 Response to Automatic Calibration**

191 The dam-break models, using SRH-2D and Hydro_AS-2D, are automatically calibrated with PEST
192 to verify whether they can properly retrieve the Manning's roughness coefficient suggested by
193 Soares-Frazão (2007) and the incidence of that calibration on the water depth RMSE.

194 The automatic calibration requires experimental measurements to compare the simulations and
195 choose the best Manning's coefficient. Because the calibration time increases proportionally to
196 the number of measurements, all available measurements cannot be used. The number of
197 benchmark values is therefore set to 27, meaning one measurement at each gauge every 5 s.

198 The coarsest mesh is used for the calibration, and Manning's roughness coefficient is allowed to
199 vary between $0.005 \text{ s/m}^{1/3}$ and $0.05 \text{ s/m}^{1/3}$ for both SRH-2D and Hydro_AS-2D.

200 **4 Results and Discussion**

201 **4.1 Time Step and Mesh Sensitivity—SRH-2D**

202 Figure 4 presents the evolution of RMSE relative to time step refinement for each gauge and
203 each mesh and shows a quick stabilization of the RMSE for the coarsest mesh, whereas the
204 finest mesh has a drastic reduction of its error between the first and fourth time steps (ex: from
205 0.0182 m to 0.0092 m for gauge 3). The error is insignificantly modified between the fourth and
206 fifth time steps (from 0.0092 m to 0.0087 m for gauge 3); these solutions can then be
207 considered to have reached time step independence.

208 The fifth time step gives the best solution for all meshes. It is used to compute the evolution of
209 water depth RMSE relative to mesh refinement, which can be observed in figure 5, and
210 diminishes with the mesh density (from 0.0094 m to 0.0087 m for gauge 3).

211 These results conform to theory because the time step needed to ensure stability, and
212 convergence is reduced proportionally to the grid size. SRH-2D has a good response to time step
213 and mesh density refinement.

214 **4.2 Mesh Sensitivity—Hydro_AS-2D**

215 Hydro_AS-2D continuously adjusts the time step during the simulation to ensure numerical
216 stability. Therefore, only the mesh sensitivity is addressed. Figure 6 shows a global reduction of
217 RMSE following the mesh refinement with the exception of gauges 1 and 3, which present a
218 slight increase for the fourth mesh (0.0004 m for gauge 1 and 0.0001 m for gauge 3). Similar
219 results were published by Družeta et al. (2009) and Boz et al. (2014), who respectively
220 investigated the influence of mesh density on the resolution of shallow water equations with

221 the Q-scheme and the MUSCL–Hancock scheme and on the resolution of the Navier–Stokes
222 equations with the CFD code ANSYS CFX.

223 **4.3 Water Depth Profiles and Oscillations**

224 Figure 7 shows the evolution of water depth in time for all meshes at gauge 1 as calculated by
225 Hydro_AS-2D. The mesh refinement greatly benefits the results for the first 15 s of the
226 simulation where the experimental and computed water depths become very similar. However,
227 the refinement seems to increase the oscillation amplitude beyond the 15th second. These
228 oscillations are not physically representative when compared to the experimental line. This
229 phenomenon may also be noted at a smaller scale for gauge 2 but is absent at gauge 3, which
230 may be because these oscillations are induced by the wall reflection. This phenomenon was also
231 noted by Družeta et al. (2009), who observed that the oscillation amplitude was increasing with
232 increasing mesh refinement but observed no dependence between the oscillation frequency
233 and the mesh density, which is not the case of the current study in which lower spatial
234 resolution seems to yield a higher oscillation frequency (figure 7).

235 SRH-2D has its general water depth results greatly improved by the mesh refinement, whereas
236 the experimental and computed depths become closer (figure 8). The augmented spatial
237 resolution also gives a better representation of the oscillations. Moreover, these oscillations are
238 offset in time but stay physically consistent with the experimental data unlike Hydro_AS-2D.

239 Comparing figures 7 and 8, Hydro_AS-2D seems to provide a better fit with the experimental
240 data for all meshes, especially for the first 15 s.

241 **4.4 Water Depth RMSE**

242 Figure 9 shows a comparison of computed water depth RMSEs for SRH-2D and Hydro_AS-2D
243 with all four meshes. The smallest time step is used for all SRH-2D simulations because it
244 provides the best results. For all meshes, Hydro_AS-2D is more accurate at all gauges and all
245 meshes, and the most important difference between the two models' RMSE is observed at the
246 third gauge (0.0094 m for SRH-2D versus 0.0038 m for Hydro_AS-2D with the coarsest mesh).
247 SRH-2D has its largest error at gauge 3, which is initially dry and may represent the difficulty of
248 modeling the wave propagation on a dry bed. This was noted as a current difficulty in numerical
249 modeling by Soares-Frazão (2007) and was one of the main purposes of the experiment used in
250 the current study. Hydro_AS-2D shows the most important error at gauge 2, which is placed
251 after the downstream side of the sill. This may be because the important slope of the sill creates
252 a flow that is not fully 2D and is therefore more difficult to represent by the model.

253 **4.5 Computation time**

254 Computation time is highly related to the number of mesh elements and time steps. Only mesh
255 density influence is studied for Hydro_AS-2D because the model automatically adjusts the time
256 step. SRH-2D gives full control of these two parameters, so both mesh density and time step
257 sensitivity are considered.

258 Figure 10 shows the evolution of computation time relative to the time step of all meshes for
259 SRH-2D. The computation time increases with increasing mesh and time step resolutions. There
260 is a dramatic increase in the computational time for time step 5 (0.0001 s) compared with time
261 step 4 (0.0004 s), especially for the finest mesh (11.6 h versus 39.1 h).

262 Because the time step has such a drastic influence on the computation time, this parameter
263 must be properly chosen to form a reliable comparison and avoid the use of a very small time

264 step that would unnecessarily increase the computation time. Therefore, the chosen time step
265 for SRH-2D is the one allowing time step independence of the model and is selected based on
266 the results of figure 4 (section *Time Step and Mesh Sensitivity*). Table 3 summarizes the time
267 step used for the two models in the computation time comparison. The computation times are
268 pretty much equal for the first mesh, but Hydro_AS-2D is generally faster by an average factor of
269 7.51 h/h (figure 11). One should note that the largest difference is observed for the finest mesh
270 where Hydro_AS-2D is 15.8 times faster, whereas the time step is almost the same for both
271 models ($\Delta t_{\text{SRH-2D}}=0.0004$ s and $\Delta t_{\text{HYDRO_AS-2D}}=0.00037$ s). The capacity of Hydro_AS-2D to
272 parallelize the calculation can explain this difference between the two models. The code
273 structures may also impact the computation time, but this information is not available for these
274 models.

275 **4.6 Response to Calibration**

276 Table 4 summarizes the results and parameters of the automatic calibrations with PEST for the
277 two models. SRH-2D necessitates 10 iterations and 38 model calls, whereas Hydro_AS-2D
278 completes the calibration in 3 iterations and 19 model calls. SRH-2D is slightly faster (1.08 h
279 versus 1.2 h), which is not surprising considering that this model has been shown to be faster for
280 the coarsest mesh, the only mesh used for the automatic calibration, when used with a time
281 step of 0.005 s (see section *Computation Time*).

282 Automatic calibration with Hydro_AS-2D provides Manning's roughness coefficient of 0.0096
283 $\text{s/m}^{1/3}$, which is very similar to 0.011 $\text{s/m}^{1/3}$ as suggested by Soares-Frazão (2007). SRH-2D, when
284 calibrated, gives a very different value of 0.0219 $\text{s/m}^{1/3}$. Hydro_AS-2D provides very similar
285 RMSEs with calibrated and suggested Manning's roughness coefficients; the maximal difference
286 is 0.0003 m, which is observed at gauge 3. This is consistent with the fact that the calibrated

287 Manning's coefficient is very close to the suggested coefficient. Therefore, Hydro_AS-2D has a
288 good response to automatic calibration. When calibrated, SRH-2D shows a greater improvement
289 of its RMSE, which decreases by up to 0.0032 m at gauge 2. If only the water depth RMSE is
290 considered to qualify the automatic calibration, SRH-2D seems to be benefiting from a
291 Manning's roughness coefficient that is approximatively twice the suggested coefficient. This is
292 unlikely because that parameter would lose its physical representativeness of the actual
293 channel's roughness. This is confirmed by the observation of the evolution of water depth in
294 time at gauge 1 (figure 12). The calibrated computed water depth becomes closer to the
295 experimental water depth in the second half of the experiment; however, it is clear that the
296 shape of oscillation is lost with the calibration and is better represented by the original
297 suggested Manning's coefficient. Despite the reduced water depth RMSE, the automatic
298 calibration is unsuitable for SRH-2D in that case. One can note that Hydro_AS-2D remains
299 generally more accurate than SRH-2D, the only exception being gauge 2 at which SRH-2D gives a
300 smaller RMSE.

301 **5 Conclusion**

302 Two flood propagation models, Hydro_AS-2D and SRH-2D, were compared in terms of their
303 capacity to properly model an experimental dam-break test case. The two models were shown
304 to have a good response to mesh and time step refinement; however, Hydro_AS-2D showed
305 unphysical oscillations and an increase in the water depth RMSE at two of the three gauges with
306 the finest mesh. These observations support the idea that too much spatial resolution could
307 negatively affect the accuracy of a model as noted by Družeta et al. (2009) and Boz et al. (2014).
308 Hydro_AS-2D computed lower RMSEs for all meshes and was therefore more accurate than
309 SRH-2D. Hydro_AS-2D was up to 15.8 times faster than SRH-2D. This contrasts with the results

310 of Tolossa (2008) and Tolossa et al. (2009), who found that SRH-W (the previous version of SRH-
311 2D) was faster than Hydro_AS-2D. Hydro_AS-2D responded well to the automatic calibration of
312 Manning's roughness coefficient by computing a coefficient very similar to the suggested one,
313 whereas SRH-2D computed a very different coefficient that lowered the water depth RMSE but
314 with no physical representativeness of the actual channel.

315 This research has exposed some of the differences between two major hydrodynamic models
316 and clarified their respective assets to offer an objective point of comparison that will be helpful
317 for industrial and research engineers in choosing a modeling tool for flood propagation.

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386 **Figure Captions**

387 **Fig. 1.** Automatic calibration with PEST – Adapted from Lin (2010)

388 **Fig. 2.** Channel geometry, initial conditions and gauges positions

389 **Fig. 3.** Meshes (0.5 m × 0.45 m zone)

390 **Fig. 4.** Water depth RMSE relative to time step refinement at Gauges 1-3—SRH-2D

391 **Fig. 5.** Water depth RMSE relative to mesh refinement—SRH-2D

392 **Fig. 6.** Water depth RMSE relative to mesh refinement—Hydro_AS-2D

393 **Fig. 7.** Water depth at gauge 1 for meshes 1-4—Hydro_AS-2D

394 **Fig. 8.** Water depth at gauge 1 for meshes 1-4—SRH-2D

395 **Fig. 9.** Comparison of computed water depth RMSEs—Meshes 1-4

396 **Fig. 10.** Computation time relative to time step refinement—SRH-2D

397 **Fig. 11.** Comparison of computation time

398 **Fig. 12.** Comparison of water depth with suggested and calibrated Manning’s coefficients at
399 gauge 1—SRH-2D

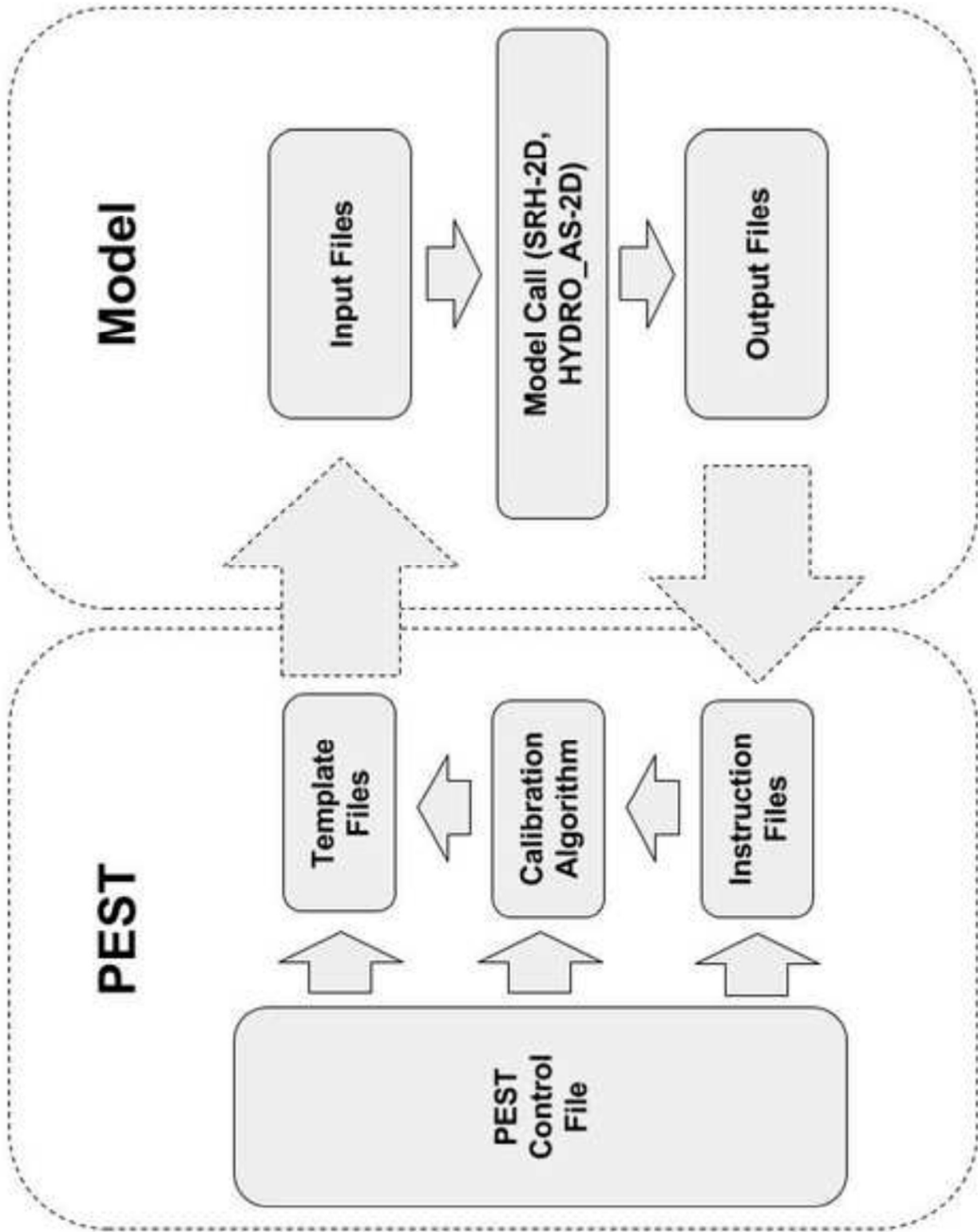
400 **Table Captions**

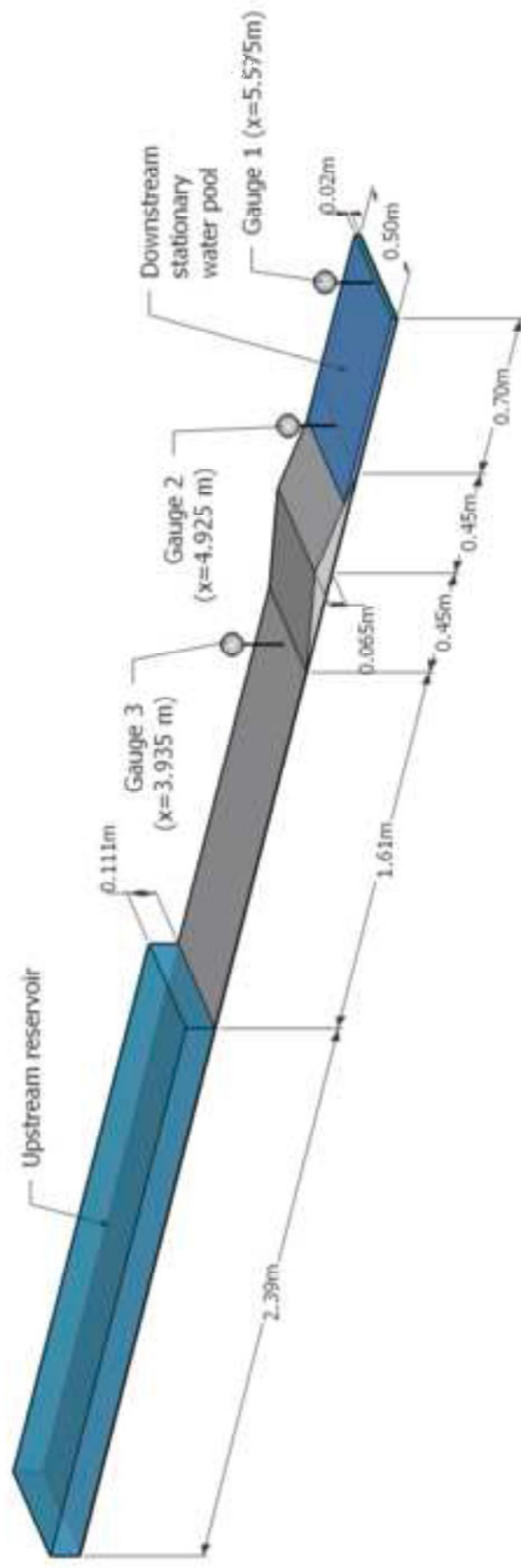
401 **Table 1.** Time steps

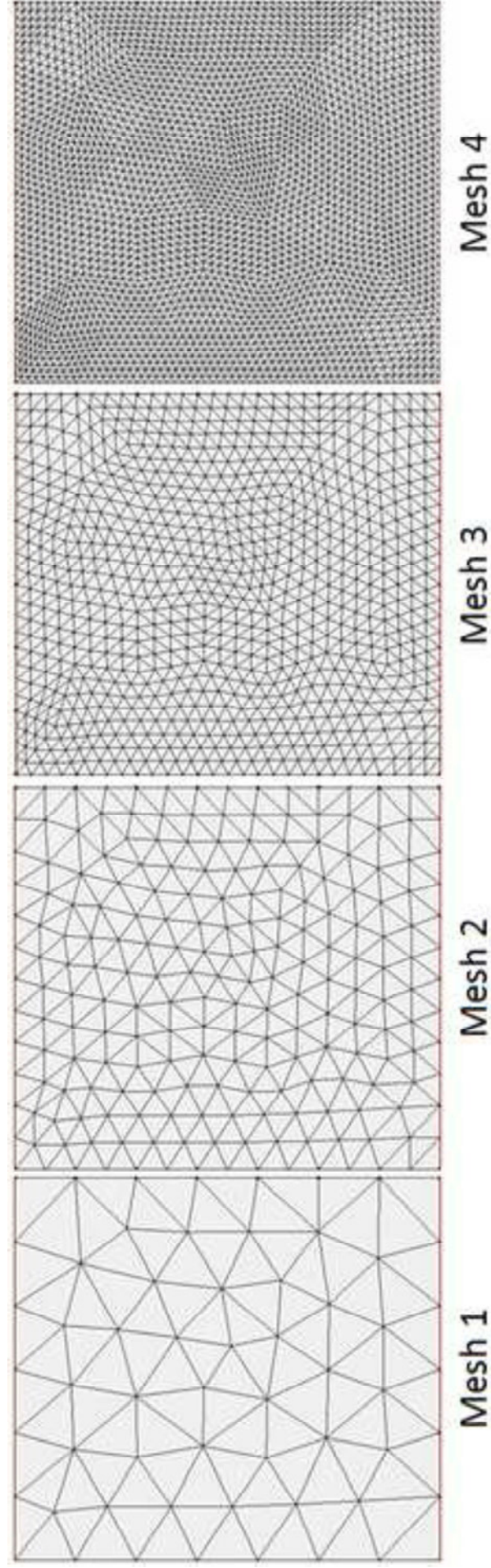
402 **Table 2.** Meshes

403 **Table 3.** Time steps used for computation time comparison

404 **Table 4.** Calibration parameters and results







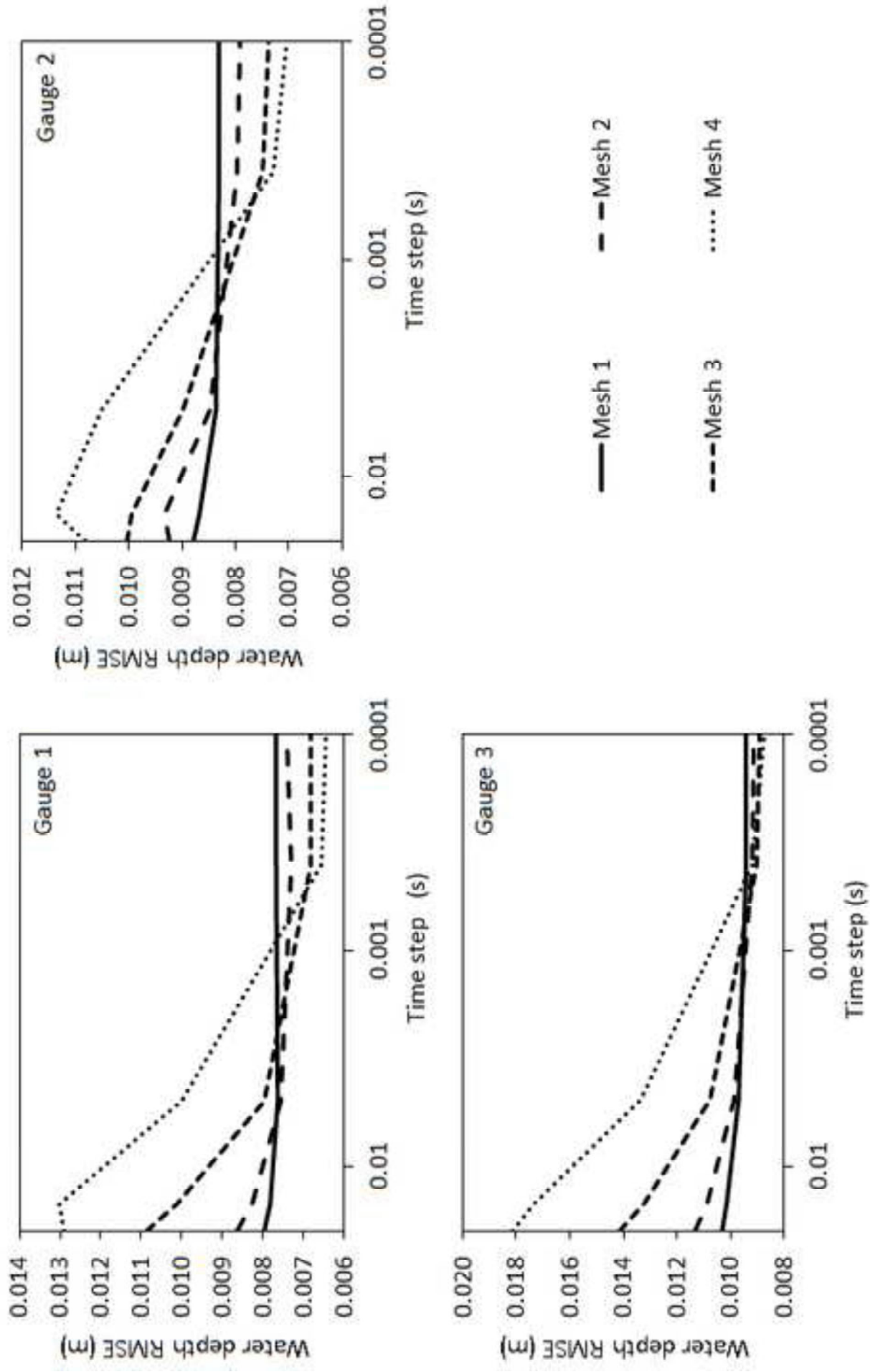


Figure 5

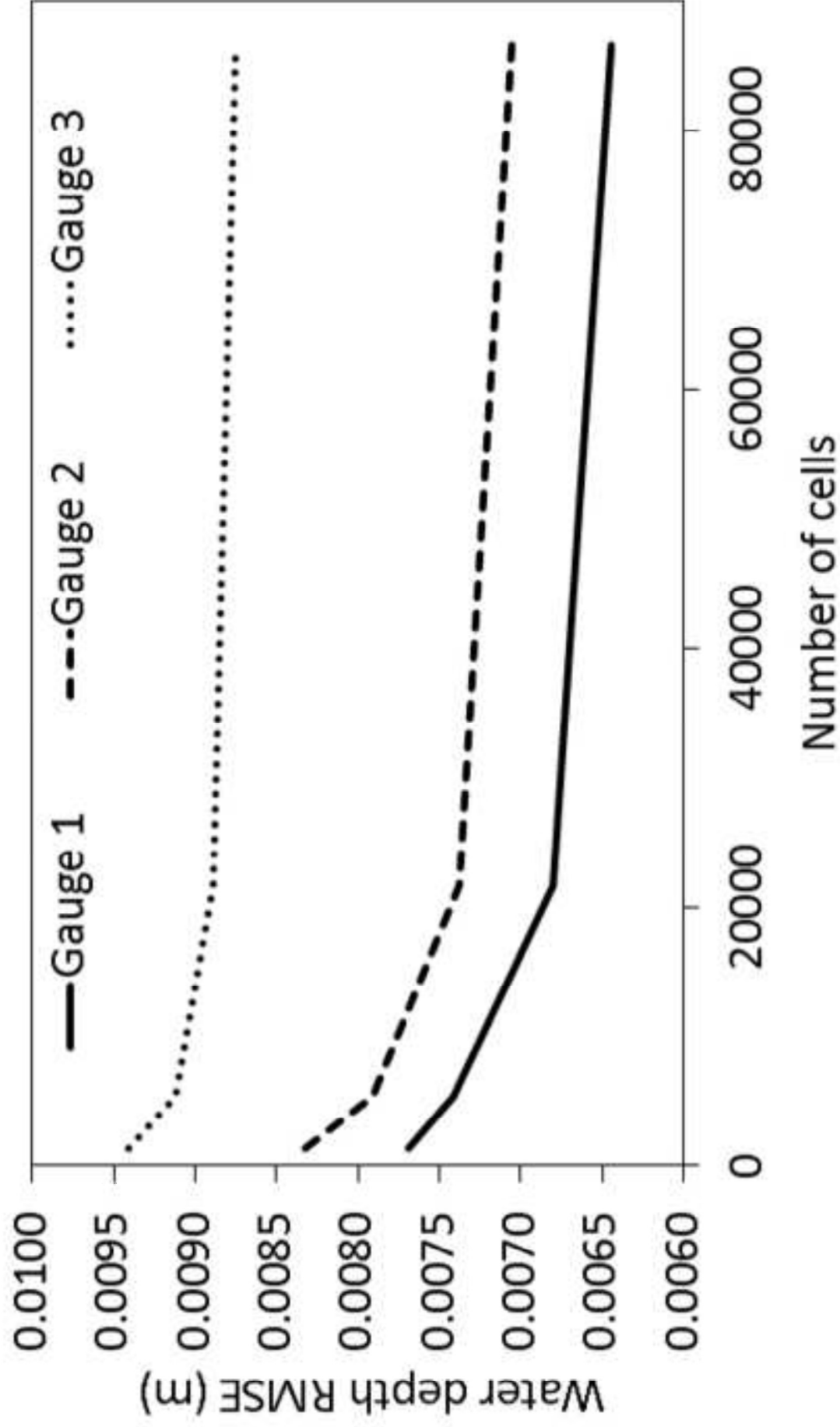
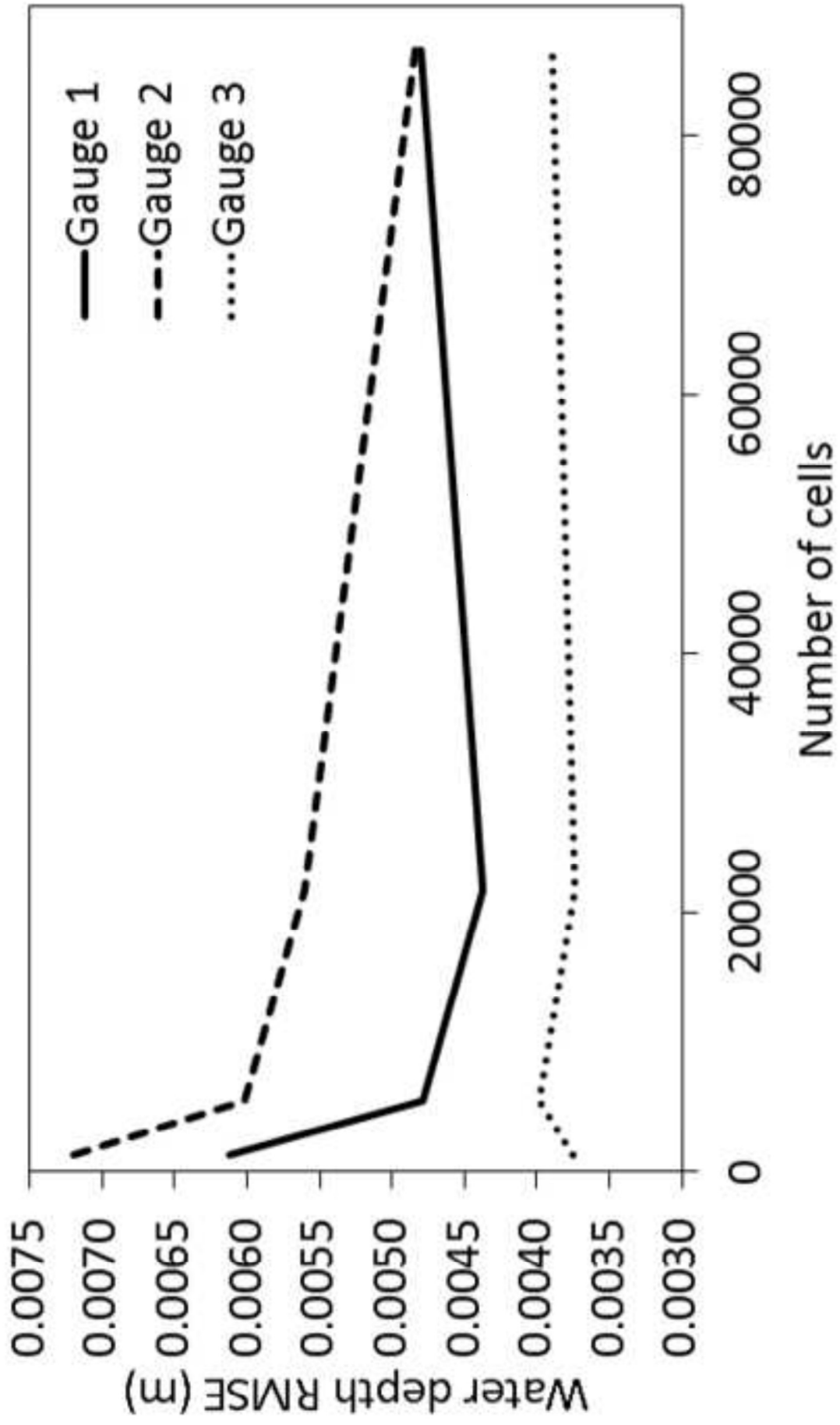
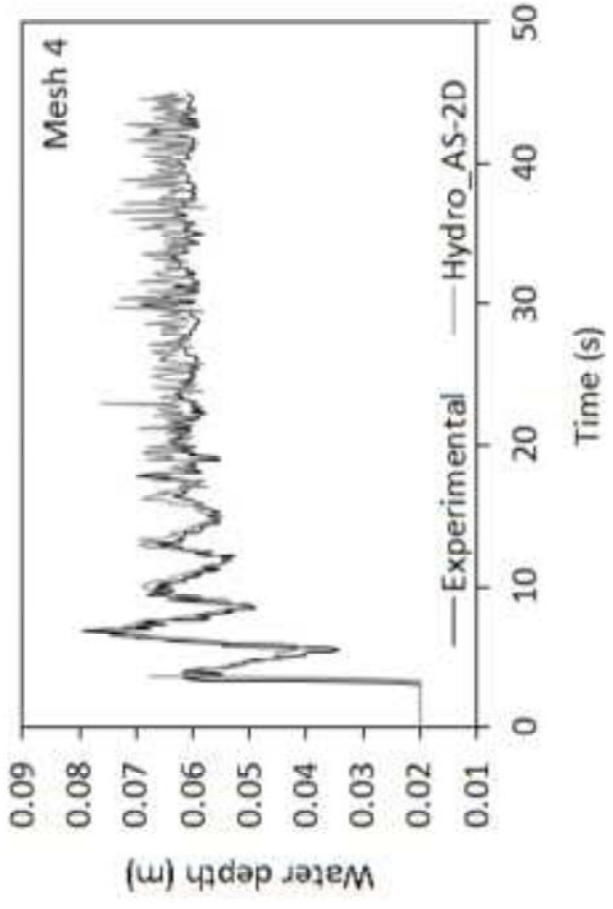
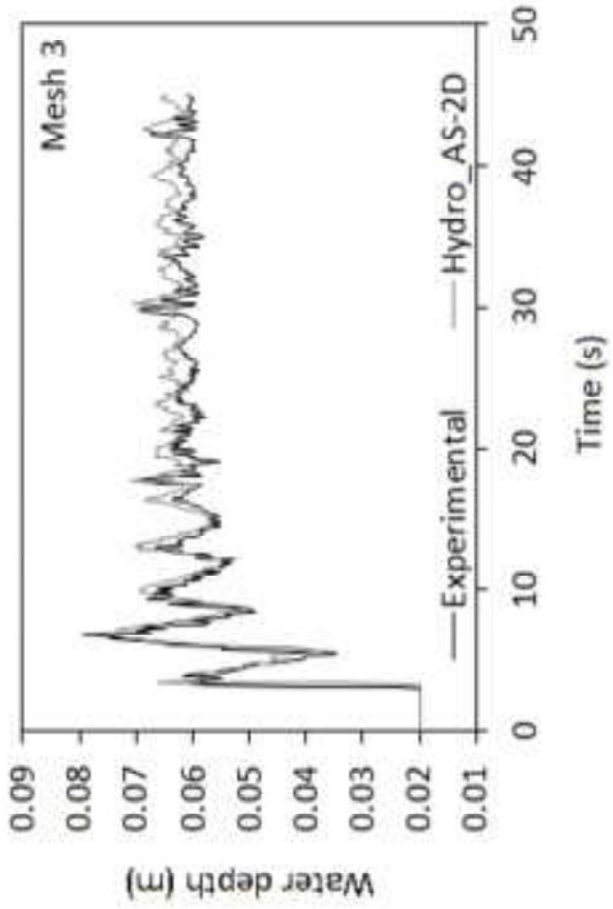
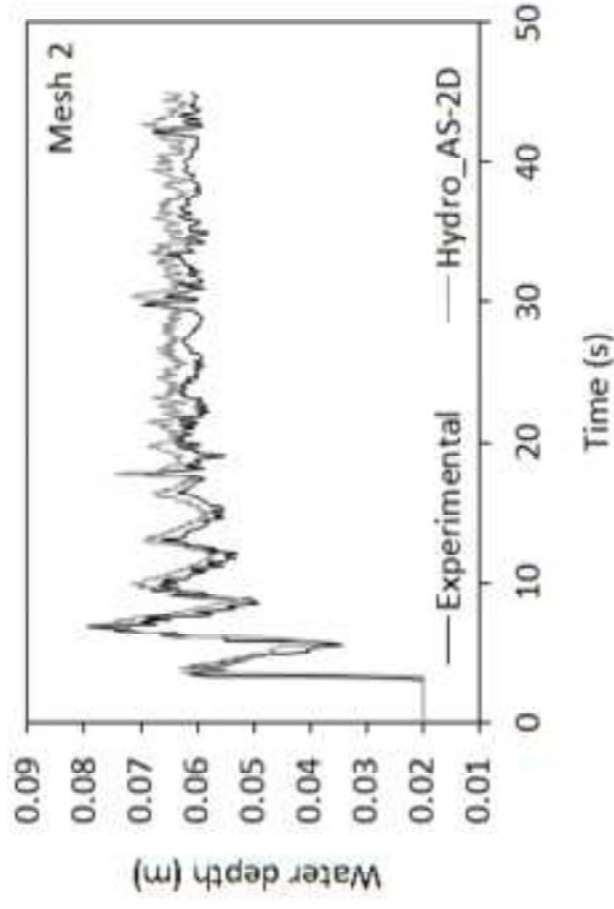
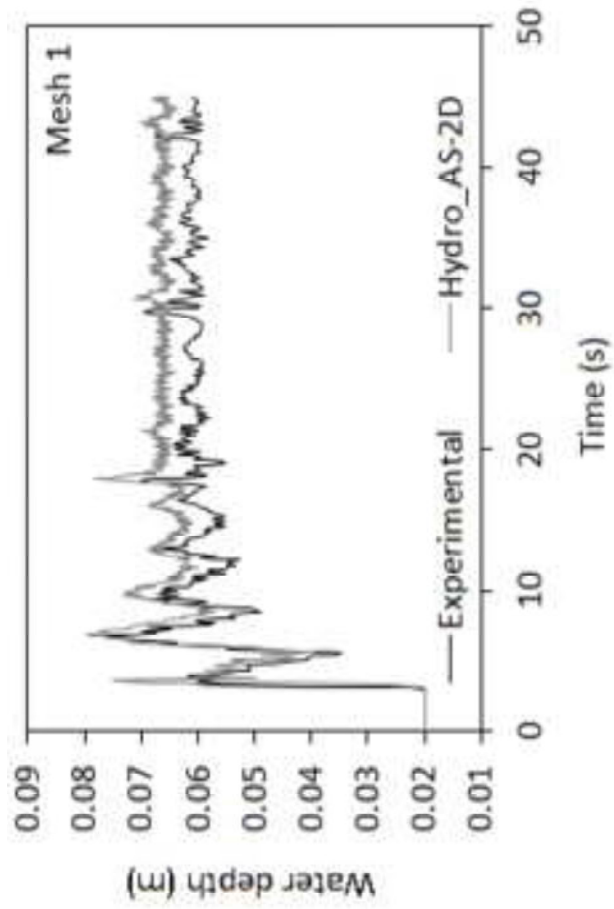
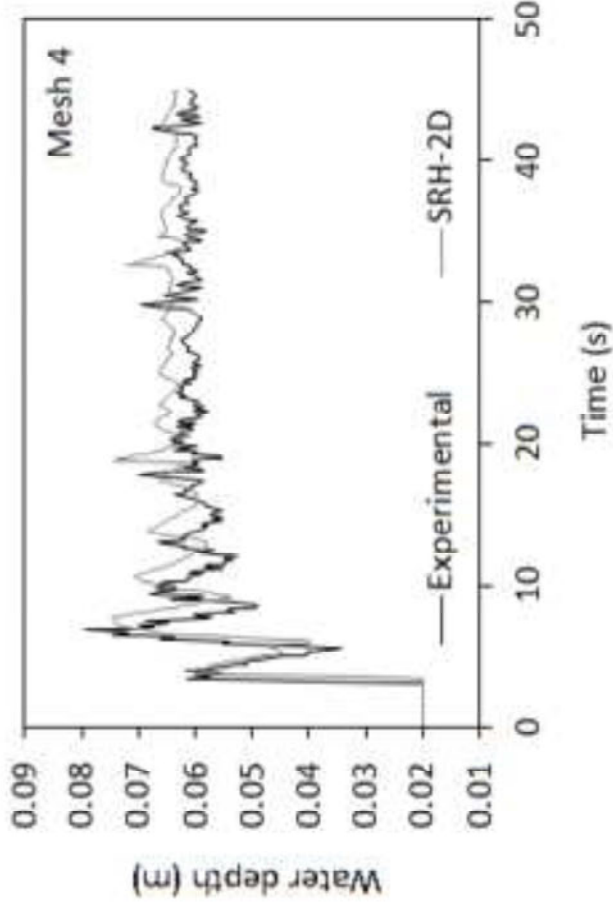
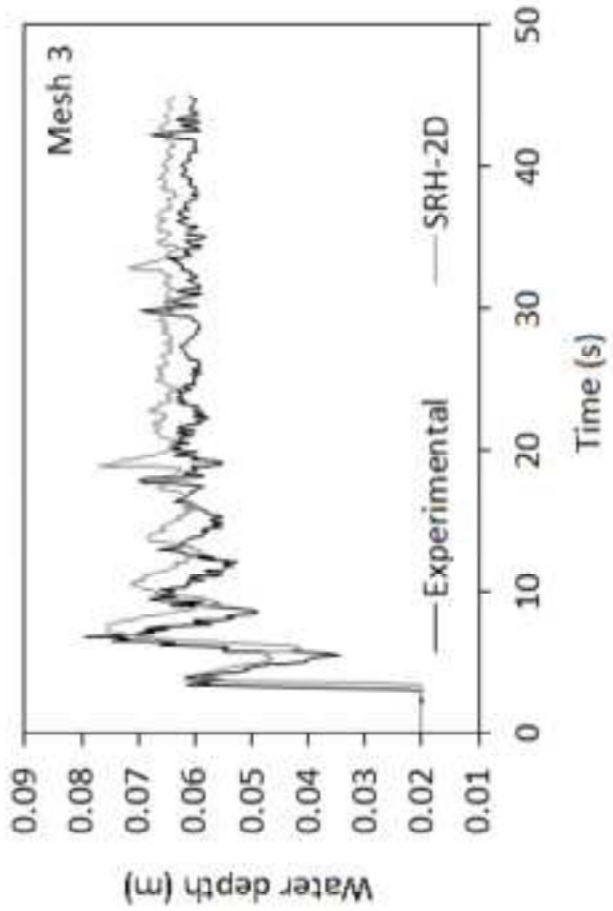
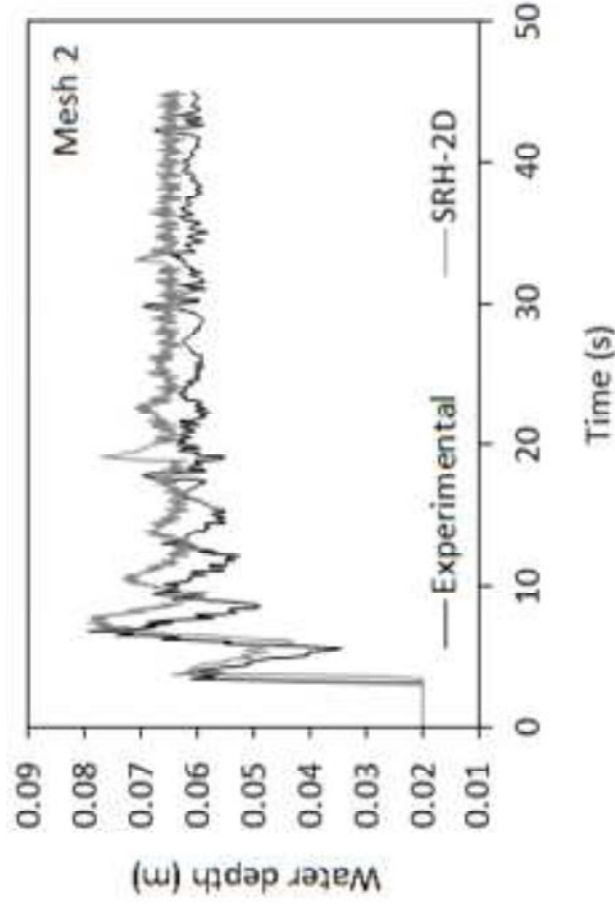
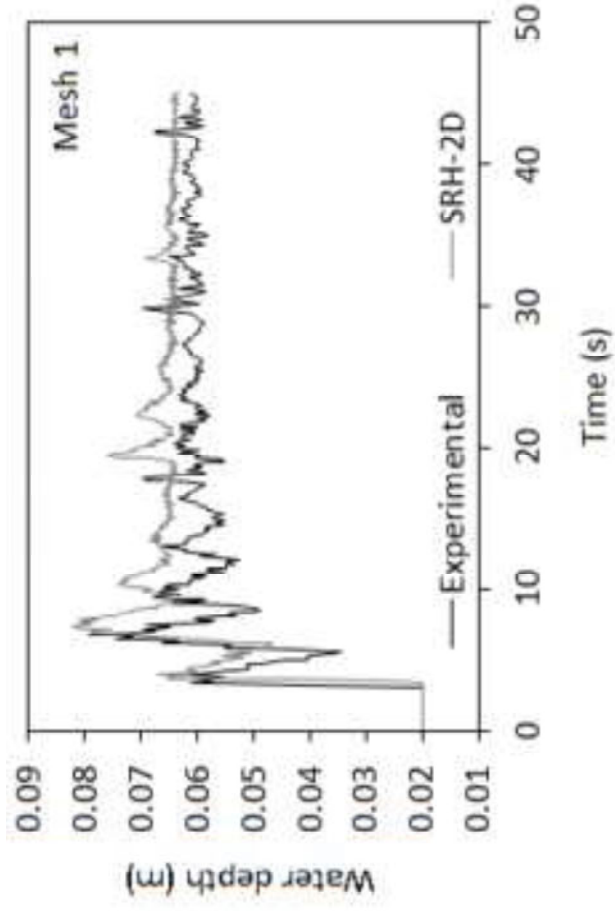
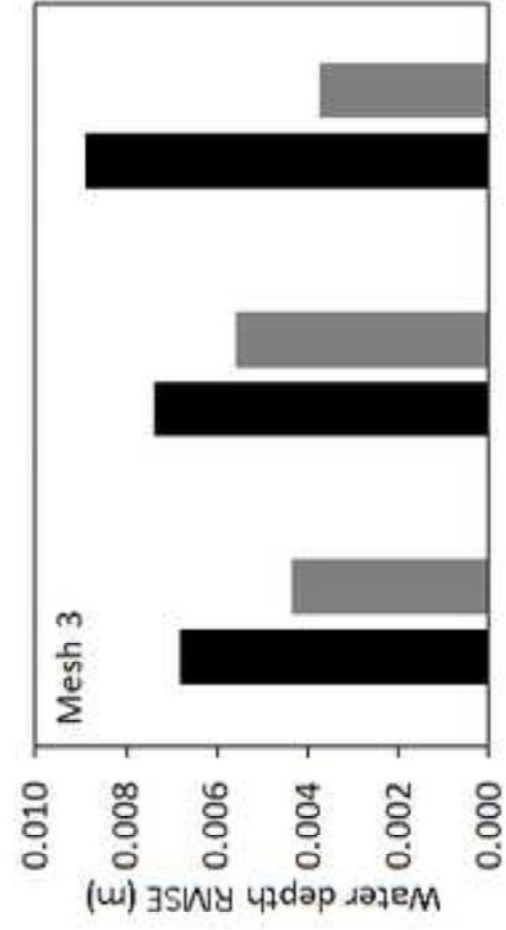
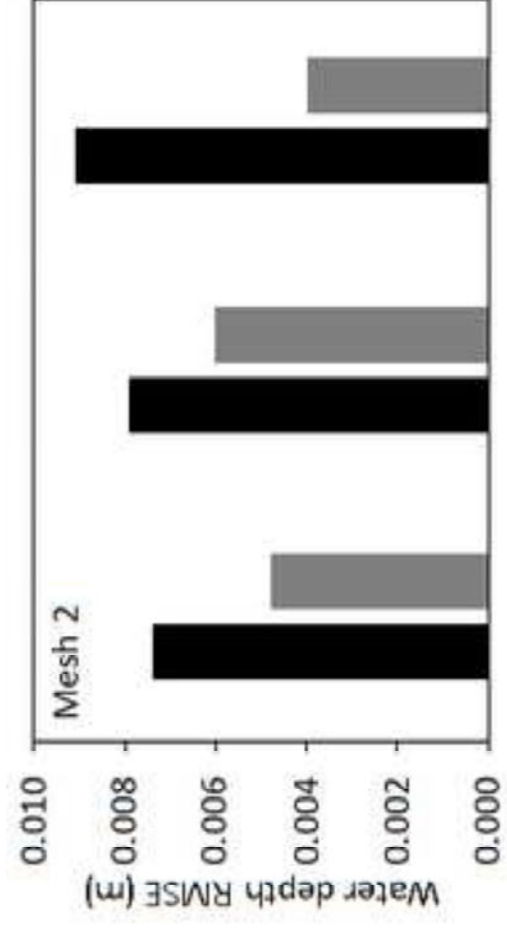
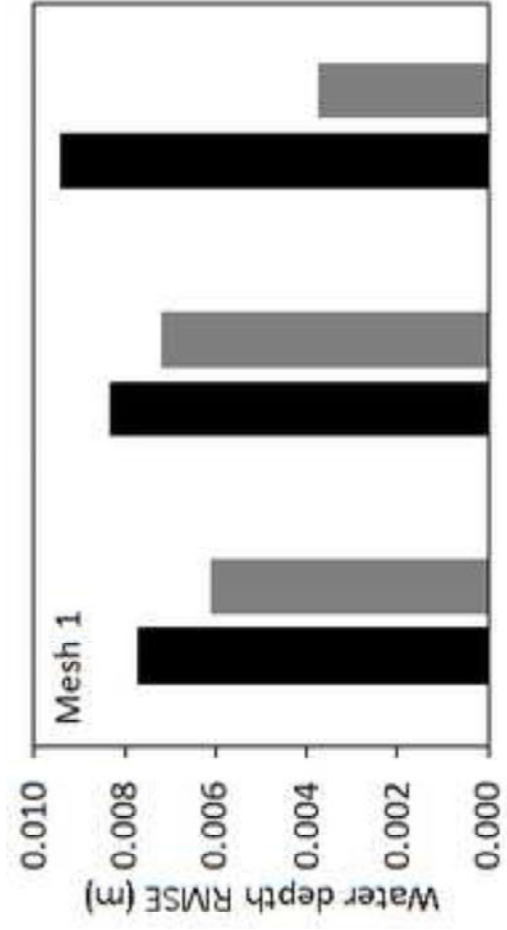


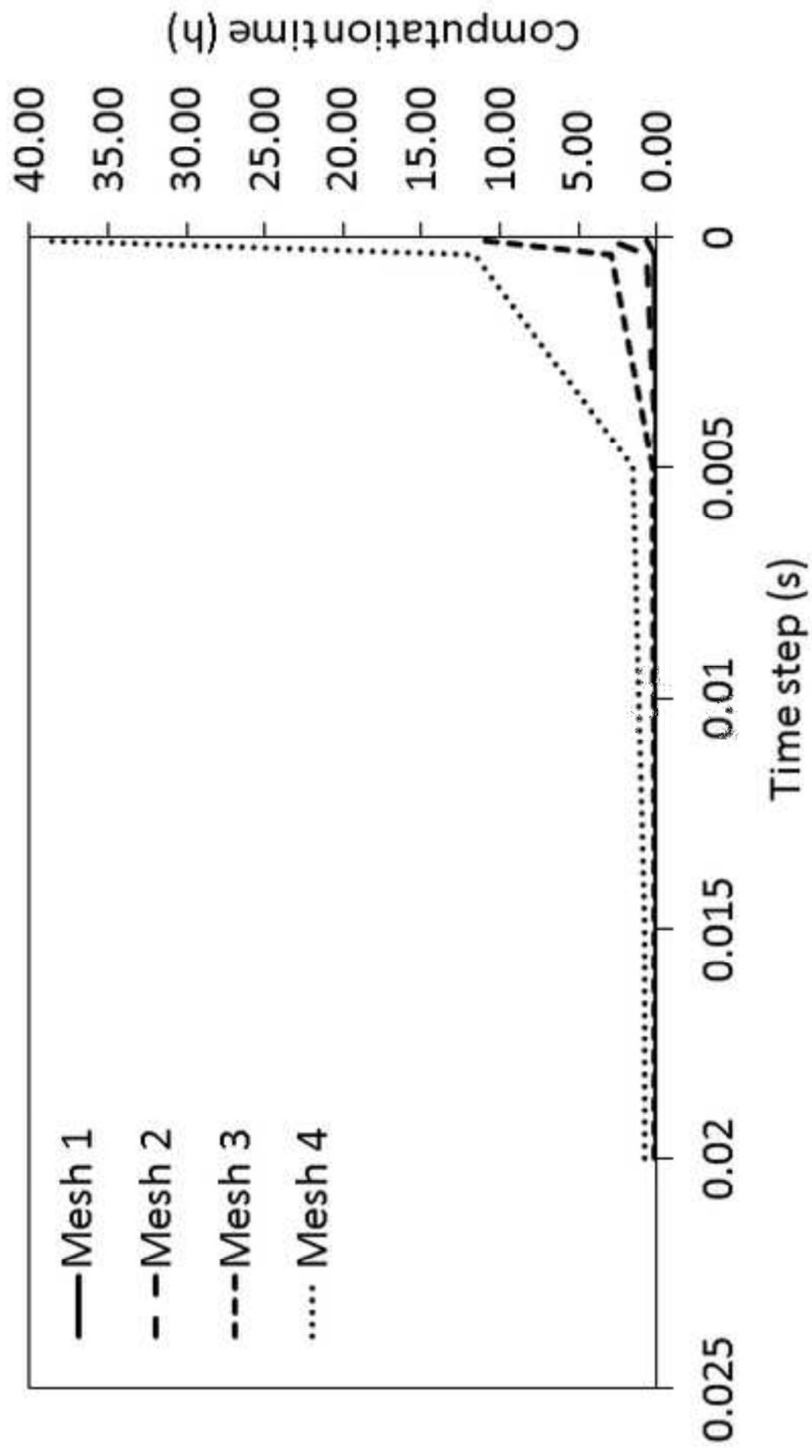
Figure 6

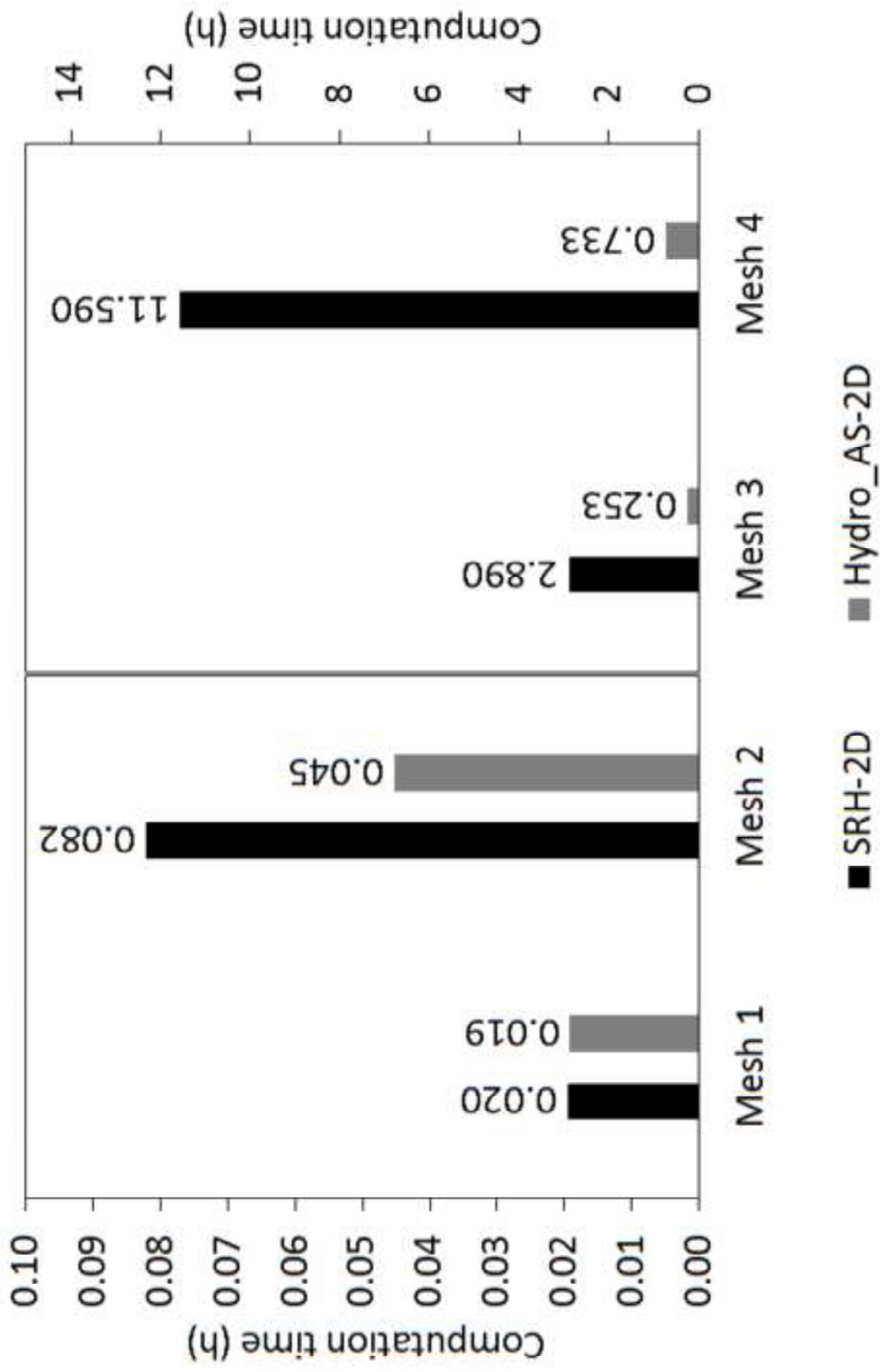












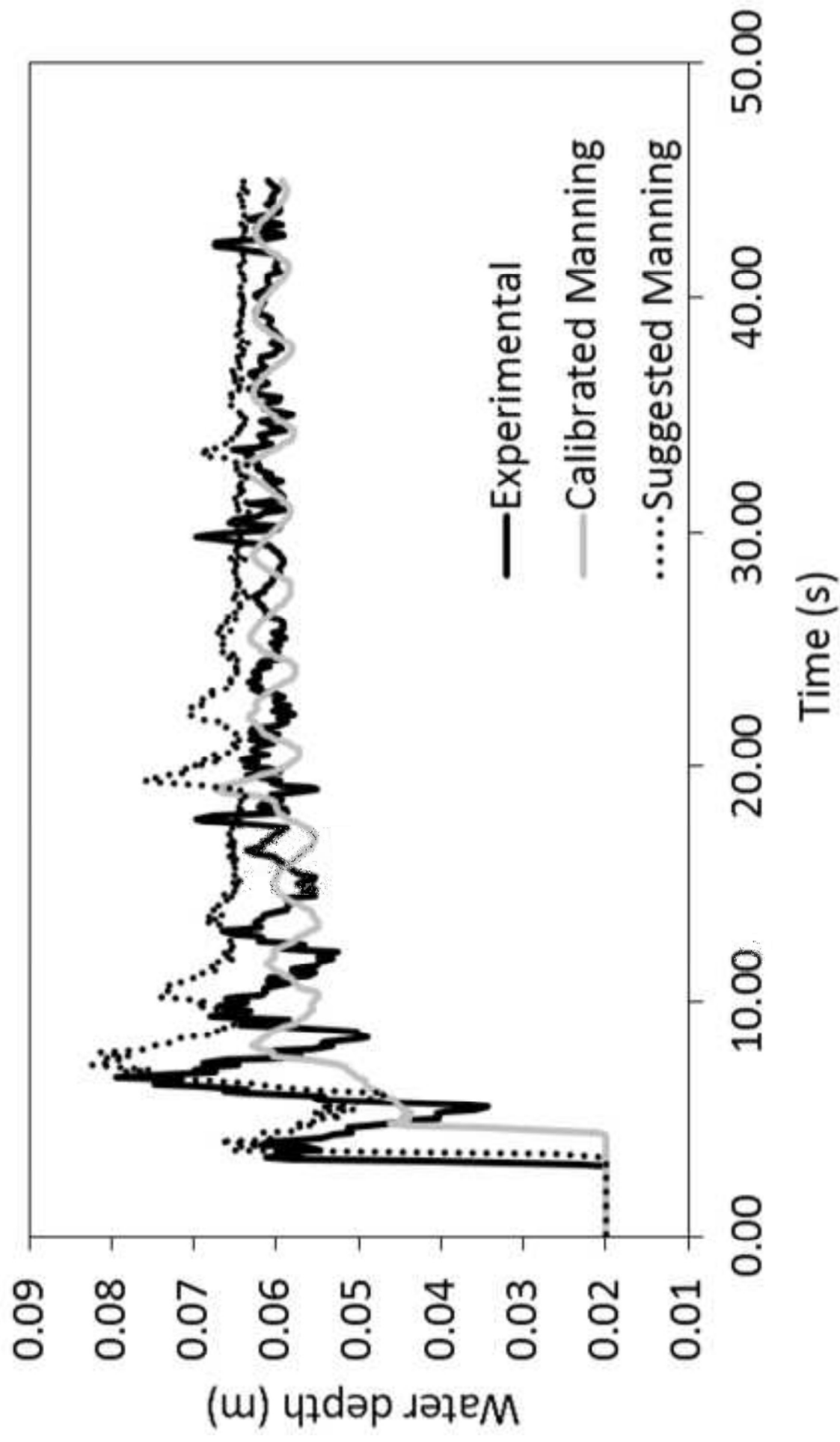


Table 1. Time steps

ID	Time Step (s)
1	0.02
2	0.015
3	0.005
4	0.0004
5	0.0001

Table 2. Cells' number for the different meshes

ID	Number of Cells
1	1 353
2	5 412
3	21 648
4	86 592

Table 3. Time steps used for computation time comparison

	SRH-2D (s)	Hydro_AS-2D (s)
Mesh 1	0.005	0.020691
Mesh 2	0.005	0.001282
Mesh 3	0.0004	0.001675
Mesh 4	0.0004	0.000369

Table 4. Calibration parameters and results

	SRH-2D		Hydro_AS-2D	
	Calibrated n	Suggested n	Calibrated n	Suggested n
RMSE Gauge 1 (m)	0.00821	0.00765	0.00640	0.00613
RMSE Gauge 2 (m)	0.00518	0.00837	0.00739	0.00720
RMSE Gauge 3 (m)	0.00754	0.00972	0.00403	0.00375
Model calls	38		19	
Iterations	10		3	
Calibrated n (s/m ^{1/3})	0.0219		0.0096	
Suggested n (s/m ^{1/3})	0.011		0.011	
Computation time (h)	1.08		1.2	