

## Background and Objectives

- The gradient method determines soil heat flux density ( $G$ ) from the product of soil thermal conductivity ( $\lambda$ ) and temperature ( $T$ ) gradient at a soil depth below surface.

$$G = \lambda (dT / dz) \quad [1]$$

- Heat-pulse (HP) probes have been used to measure  $\lambda$ . Its accuracy is influenced by soil-air interface, soil-probe contact resistance, and ambient temperature drift near surface.
- Thermal conductivity models can estimate  $\lambda$  with sufficient accuracy from information of soil texture, bulk density ( $\rho_b$ ), and water content ( $\theta$ ).

- The **objectives** of this study are to evaluate:

- ✓ the potential of estimating near-surface  $G$  using modeled thermal conductivity ( $\lambda_m$ ) with the gradient method, and
- ✓ the influences of  $\theta$  and  $\rho_b$  on  $\lambda_m$  and  $G$  results.

## Materials and Methods

- Field site:** A bare sandy loam soil (79.8, 7.7, and 12.5% sand, silt, and clay contents, respectively) in the experimental farm of China Agricultural University.

- Measurements (Fig. 1):**

- ✓ Field measurements lasted for 25 d (DOY 253-278);

- ✓  $G$  at 2, 6, and 10 cm were determined with two approaches: gradient method using measured  $\lambda_{HP}$  and gradient method using modeled  $\lambda_m$ .

- Soil heat flux calculations (Eq. 1, Fig. 1):**

- ✓ Using measured  $\lambda_{HP}$

$$G_{HP} = -\lambda_{HP} \times (\Delta T_{HP} / \Delta z)$$

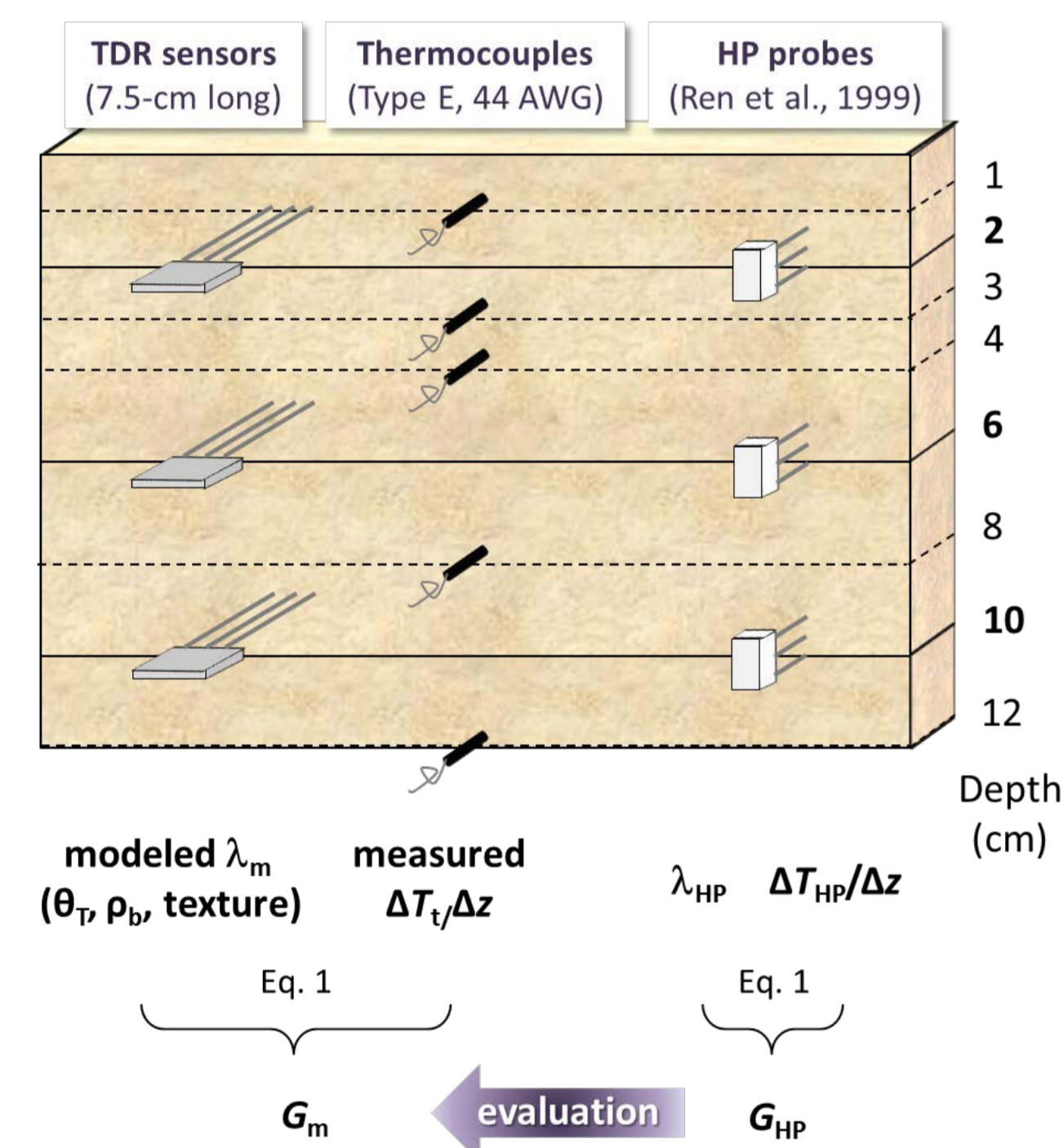
- ✓ Using modeled  $\lambda_m$  from L07

$$G_{m-L07} = -\lambda_{m-L07} \times (\Delta T_i / \Delta z)$$

- ✓ Using modeled  $\lambda_m$  from L14

$$G_{m-L14} = -\lambda_{m-L14} \times (\Delta T_i / \Delta z)$$

Fig. 1. Sensor installation.



Parameter	Depth (cm)	Interval	Equipment/sensor
Bulk density ( $\rho_b$ )	0-5, 5-10	1.9 d	Ring samplers
Gravimetric water content ( $\theta_m$ )	2, 6, 10	1.9 d	Layering sampler (Zhang et al., 2014)
TDR water content ( $\theta_{TDR}$ )	2, 6, 10	1 h	TDR 100 and 7.5-cm long TDR probe
Thermal conductivity ( $\lambda_{HP}$ )	2, 6, 10	1 h	3-needle heat-pulse sensor
Temperature ( $T$ )	1, 3, 4, 8, 12	1 h	Thermocouple ( $T_i$ ) and 3-needle heat-pulse sensor ( $T_{HP}$ )

For heat-pulse  $\lambda_{HP}$  measurements: 1) ambient temperature drift was corrected (Jury and Bellantuoni, 1976); 2) late-time fitting scheme was used to fit the  $\Delta T(t)$  curves (Lu et al., 2013).

- The  $\lambda$  models**

L07 Model	L14 Model
$\lambda_{m-L07} = (\lambda_{sat} - \lambda_{dry})K_e + \lambda_{dry}$	$\lambda_{m-L14} = \lambda_{dry} + \exp(\beta - \theta^\alpha)$
$\lambda_{sat} = (\lambda_q^{f_{sa}} \lambda_o^{1-f_{sa}})^{1-n} \lambda_w^n$	$\lambda_{dry} = -0.56n + 0.51$
$\lambda_{dry} = -0.56n + 0.51$	$\alpha = 0.67f_{cl} + 0.24$
$K_e = \exp\{\epsilon[1 - (\theta/\theta_s)^{\epsilon-1.33}]\}$	$\beta = 1.97f_{sa} + 1.87\rho_b - 1.36f_{sa}\rho_b - 0.95$

$f_{sa}$  and  $f_{cl}$ : sand and clay fraction, respectively;  $\epsilon$ : texture dependent factor, 0.96 for coarse soils;  $n$ : total porosity ( $1 - \rho_b / 2.65$ );  $a$  and  $b$ : shape factors of the  $\lambda(\theta)$  curve

Three parameters, **texture**,  $\rho_b$ , and  $\theta$ , are required for  $\lambda$  modeling.

## Results and Discussions

### 1. Time series of $G_m$ and $G_{HP}$

- $G_m$  and  $G_{HP}$  followed the same trend and showed similar responses to rainfall and diurnal solar radiation (Fig. 2), with the magnitude of  $G$  decreasing with soil depth;
- $G_m$  and  $G_{HP}$  ranged from -70 to 210  $W m^{-2}$  and -70 to 220  $W m^{-2}$  at 2 cm, respectively;
- $G_m$  and  $G_{HP}$  reduced to -50 to 160  $W m^{-2}$  at 6 cm, and to -50 to 130  $W m^{-2}$  at 10 cm.

### 2. Comparison of $G_m$ and $G_{HP}$

- $G_m$  agreed well with  $G_{HP}$  at three depths (with RMSE of 5.7-9.1  $W m^{-2}$ , Table 1). The errors were attributed to the differences between  $\Delta T_i / \Delta z$  &  $\Delta T_{HP} / \Delta z$  and between  $\lambda_m$  &  $\lambda_{HP}$ ;
- When using  $\Delta T_{HP} / \Delta z$  with  $\lambda_m$  and  $\lambda_{HP}$  for estimating  $G$  (Eq. 1),  $G_m$  errors that caused by  $\lambda_m$  errors were in the range of 1.3-6.6  $W m^{-2}$  (Table 1);
- $G_{m-L07}$  and  $G_{m-L14}$  estimates were in close agreement.

### 3. Field performance of $\lambda$ models (Table 2)

- $\lambda_m$  estimates from the L07 and L14 models were in close agreement;
- RMSEs of  $\lambda_m$ : 0.05-0.09 and 0.05-0.08  $W m^{-1} K^{-1}$  for L07 and L14 models, respectively;
- $\lambda_m$  and  $\lambda_{HP}$  discrepancy was observed at 2 cm, producing larger  $G_m$  errors.

### 4. Effect of $\rho_b$ on $\lambda$ modeling and $G$ estimate

- $\rho_b$  increased from 1.27 to 1.39 and 1.35 to 1.40  $g cm^{-3}$  in 0-5 and 5-10 cm layers, respectively;
- Using dynamic  $\rho_b$  improved the model performance. At 2 cm, for example,
  - ✓ With fixed  $\rho_{b-v}$ ,  $\lambda_{m-L14}$  deviated from  $\lambda_{HP}$  gradually (Fig. 3), with RMSE of 0.08  $W m^{-1} K^{-1}$ ;
  - ✓ With dynamic  $\rho_{b-v}$ ,  $\lambda_{m-L14}$  agreed well with  $\lambda_{HP}$  with RMSE of 0.05  $W m^{-1} K^{-1}$ ; Therefore,
  - ✓ Improved  $\lambda_{m-L14}$  estimates using  $\rho_{b-v}$  led to improved  $G_{m-L14}$  (with RMSE decreased from 5.7 to 4.3  $W m^{-2}$ ).
- At 6- and 10-cm depths,  $\rho_b$  varied slightly and had negligible effect on  $G_m$  data.

### 5. Effect of $\theta$ on $\lambda$ modeling and $G$ estimate

- The models not only produced reliable  $\lambda$  estimates with dynamic TDR  $\theta_T$ , but also captured the abrupt changes in  $\lambda$  (Fig. 4a) and  $G$  (Fig. 4b) due to rainfall events;
- Using soil sampling  $\theta_s$ , the models gave good estimates of  $\lambda$  and  $G$  at the specific measuring moment, but missed  $\lambda$  and  $G$  dynamics shortly after rainfalls (Fig. 4a, Fig. 4b).

## Conclusions

- For the gradient method, modeled  $\lambda_m$  can be used to produced reliable near-surface  $G$ ;
- Both Lu et al. (2007) and Lu et al. (2014) models performed well in estimating field  $\lambda_m$ ;
- Comparing with the gravimetric method, the TDR technique has the advantage of capturing the dynamics of  $\theta_T$ , thus provides continuous  $\lambda_m$  and  $G_m$  shortly after rainfalls.
- For near-surface layers (i.e., within 2 cm), it is necessary to include the temporal variations of  $\rho_b$  for estimating  $\lambda_m$  and  $G_m$  accurately.
- With the modelling approach, one can estimate soil heat flux density  $G$  using existing measurements of soil water content, temperature, and bulk density, which eliminates the needs of measuring thermal conductivity with complicated equipment.

## References

- Lu, S., Ren, T., Gong, Y., Horton, R., 2007. An improved model for predicting soil thermal conductivity from water content at room temperature. *Soil Sci. Soc. Am. J.* 71(1), 8–14.
- Lu, Y.L., Lu, S., Horton, R., Ren, T., 2014. An empirical model for estimating soil thermal conductivity from texture, water content, and bulk density. *Soil Sci. Soc. Am. J.* 78:1859–1868.

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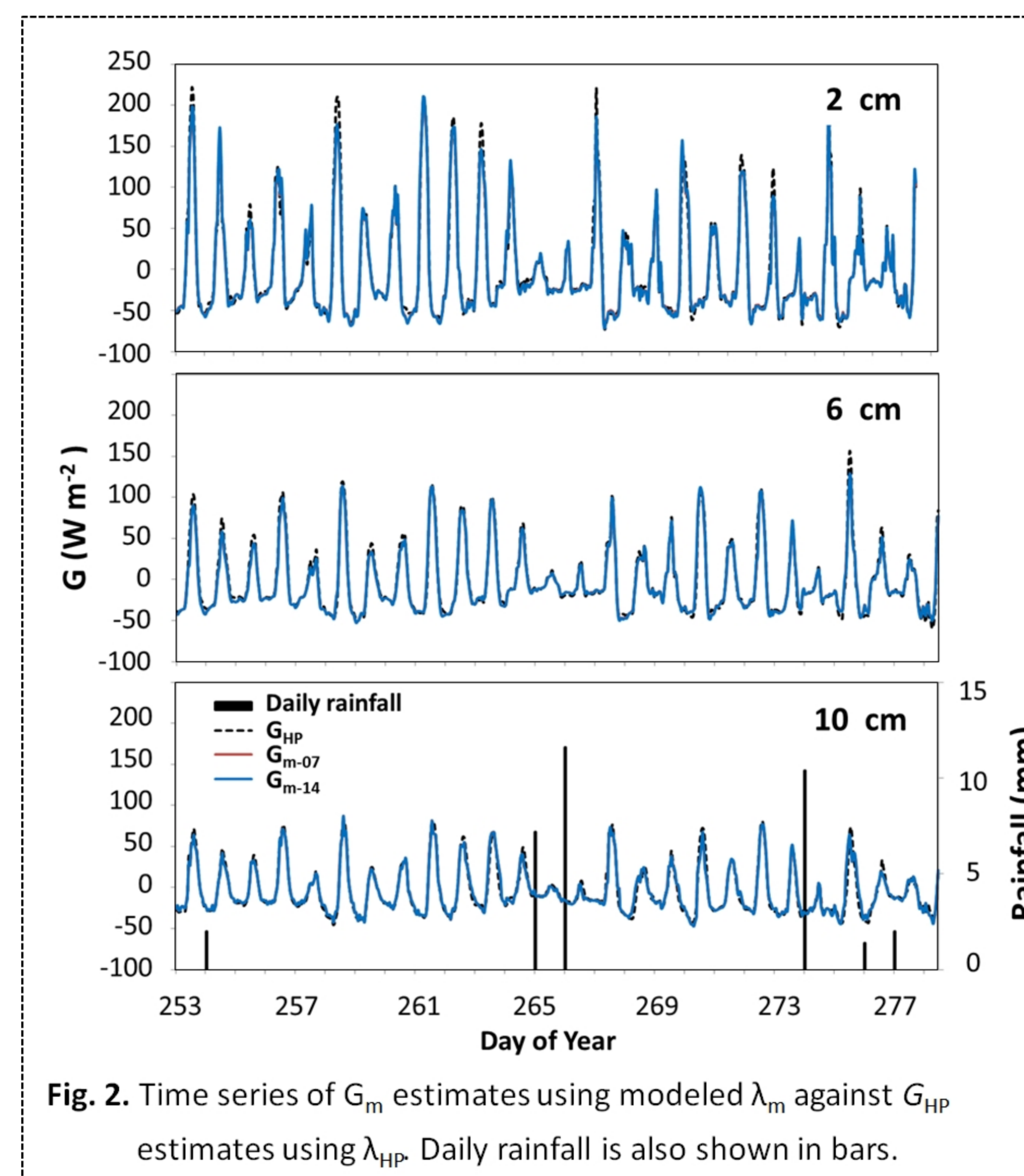


Fig. 2. Time series of  $G_m$  estimates using modeled  $\lambda_m$  against  $G_{HP}$  estimates using  $\lambda_{HP}$ . Daily rainfall is also shown in bars.

Table 1. RMSE of  $G_m$  estimates using modeled  $\lambda_m$ .

Depth (cm)	With $\Delta T_i / \Delta z$		With $\Delta T_{HP} / \Delta z$	
	L07	L14	L07	L14
2	9.1	8.9	6.6	5.7
6	5.8	5.7	1.8	1.6
10	5.8	5.9	1.3	1.3

Table 2. RMSE of modeled  $\lambda_m$ .

Depth (cm)	L07	L14
2	0.09	0.08
6	0.05	0.05
10	0.05	0.05

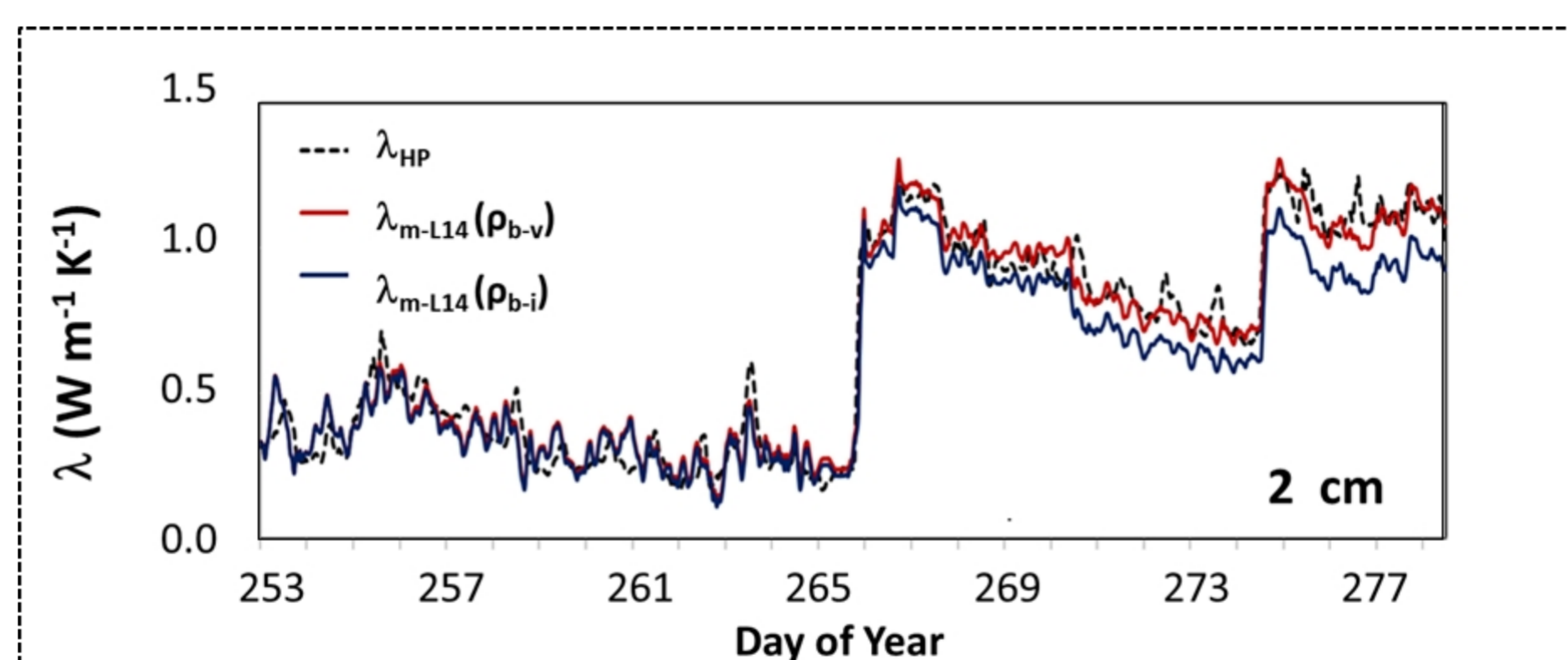


Fig. 3. Dynamics of  $\lambda_{HP}$  and modeled  $\lambda_{m-L14}$  from dynamic  $\rho_{b-v}$  values (every 1.9 d) and a fixed  $\rho_{b-1}$  (measured on DOY 253) at 2 cm.

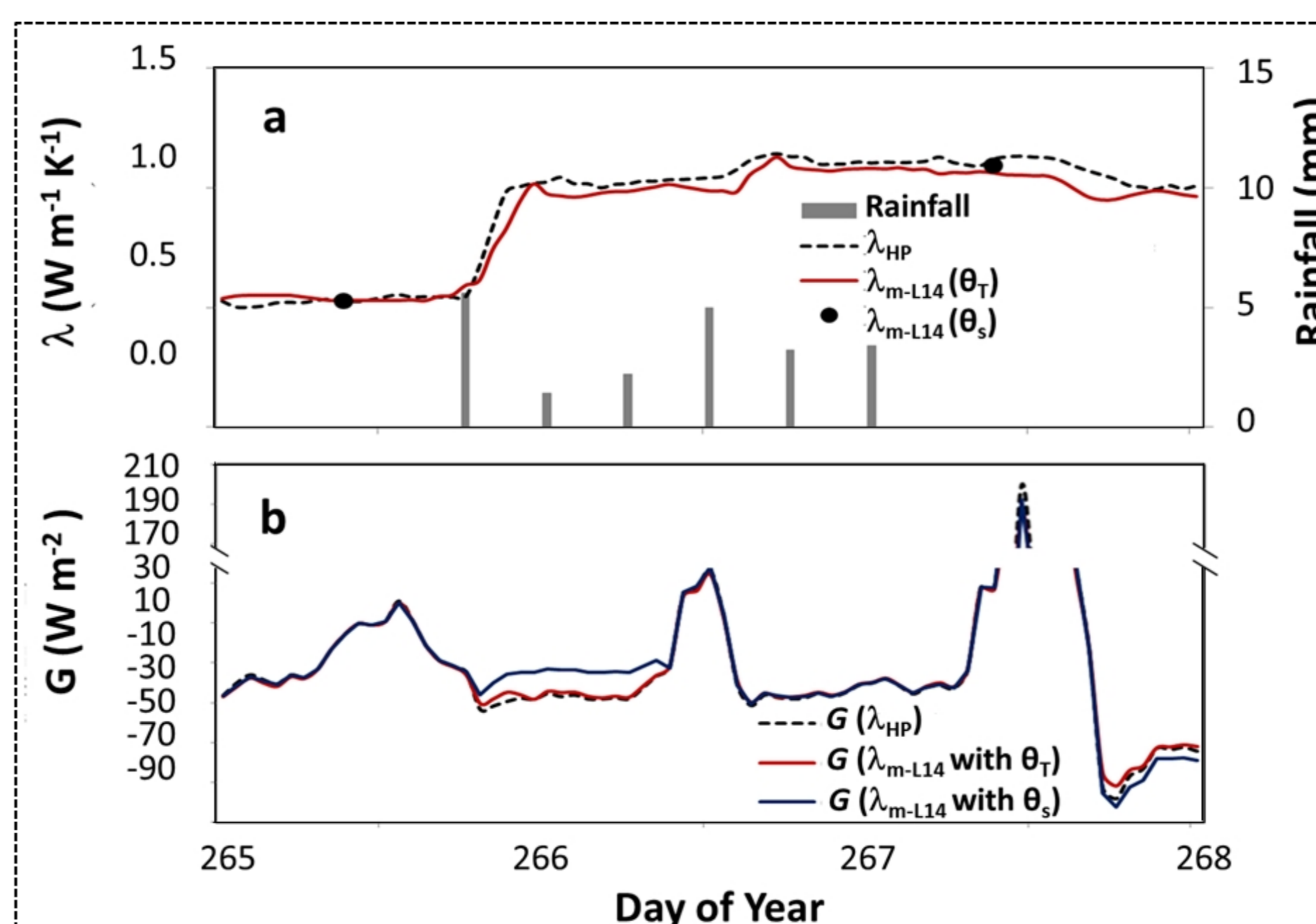


Fig. 4. a) Dynamics of  $\lambda_{HP}$  and modeled  $\lambda_m$  (with hourly  $\theta_T$  and discrete  $\theta_s$ ) at 2 cm during DOY265-268; b) time series of  $G_{HP}$  and  $G_m$  estimated with  $\lambda_m(\theta_T)$  and  $\lambda_m(\theta_s)$ .  $\Delta T_{HP} / \Delta z$  was used with both  $\lambda_{HP}$  and  $\lambda_m$  for estimating  $G_{HP}$  and  $G_m$ . Rainfall is also shown in Fig. 4a as a total of every 6 h.

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