

Revision letter: response to Reviewer #1

egusphere-2025-4531

Bayesian data selection to quantify the value of data for landslide runout calibration

December 18, 2025

We would like to thank Reviewer #1 for their valuable comments and suggestions, which improved the quality of the manuscript substantially. We present herein our responses to the comments of Reviewer #1.

Italicized line, figure, section numbers refer **to the revised manuscript**.

The changes in the revised manuscript with respect to the original manuscript can be traced in the **diff.pdf** file. Note that the line numbers in this file deviate from the pure manuscript PDF due to the tracked changes displayed.

Legend

 Shows original reviewer comment

Response Contains direct response and explanations.

Resulting changes in manuscript Summarizes resulting changes in the paper.

Contains a direct quote of new or modified manuscript content with significant changes with respect to the original manuscript.

1 Comments of Reviewer #1

1.1 General comments

1.1.1 Comment 1

The first question that comes to my mind is if the results are easily transferable from one region to another. Once a landslide occurred and observations for the calibration are available I suppose the danger of a landslide at the same location is rather low (my understanding, I am not a specialist in this field). If so what are the values of the information gathered at one site? Can they be used at other landslide-threatened locations? So, the applicability of the results should be pointed out a bit better.

Response

Thank you for this comment.

- **Regarding transferability of calibration results:** You are correct that calibration results from one landslide site are generally not directly transferable to other locations. The landslide runout models often contain conceptual parameters, that cannot be measured physically, making site-specific calibration necessary. However, we note two important caveats: (i) repeated landslide events do occur at specific sites, where calibration results can inform the design of informative prior distributions, thus improving future calibrations [Zhao and Kowalski, 2022]; and (ii) Bayesian calibration aids in building databases of parameter distributions across sites, which can enable probabilistic forecasting at sites where landslides have not yet occurred [Aaron et al., 2022].
- **Regarding the applicability of results from this paper:** This is a methodological paper rather than an application study. Our primary contribution is a systematic framework for assessing how data selection impacts Bayesian calibration of landslide runout models, essentially quantifying the value of different observational datasets for parameter estimation. We deliberately idealized the problem (simplified topography, computational model, etc.) to isolate the effect of data selection on calibration outcomes. The practical value of this work lies in enabling a priori assessment of data informativeness before costly field campaigns and calibration efforts. Researchers can use our framework with their specific topographies, runout models, and synthetic data to: (i) identify which measurements are most informative for specific parameters, (ii) optimize data acquisition strategies, and (iii) select optimal subsets from existing observational datasets. For example, our finding that the observation window with maximum information gain rate aligns with the acceleration phase (when the mass reaches maximum velocity) suggests prioritizing observations of transient dynamics. Such insights, derived from scenario testing with synthetic data, can guide cost-effective monitoring strategies tailored to specific sites and objectives.

Resulting changes in manuscript

To address the reviewer feedback, we elaborated the applicability of the work in the discussion section (*p 29. lines 524-529*).

Beyond the insights from our synthetic case study, the proposed Bayesian data selection workflow provides a systematic framework for performing a priori assessment of data informativeness before costly field campaigns. To implement this framework, practitioners should first prepare a synthetic test case using site-specific topography and their computational model. By generating candidate observational datasets through forward model evaluation at known parameters, they establish a virtual testbed for scenario-based testing that quantifies how different candidate datasets inform specific parameters of interest and tests case-specific hypotheses about data value.

1.1.2 Comment 2

There is no description of the geometry (or anything else) of the landslide model the authors used to generate the synthetic data for the experiments. This way it is hard to estimate if it is a very idealized case that is difficult to transfer to reality or not. Also, the friction parameters in the model are uniform on the entire sliding surface. How would the results look like if the sliding surface was complicated and parameters vary within the model?

Response

Thank you for the comment.

- **Regarding the geometry of the landslide model:** We acknowledge that the details of geometry used in this study can be elaborated. We have added *Figure 6* to the revised manuscript, which is reproduced here as Figure 3 for convenience. The idealized synthetic topography consists of a curved longitudinal profile that is uniform in the transverse direction.
- **Regarding the transferability of results:** This study intentionally employs simplified topography to isolate the effect of data selection on calibration outcomes—the core methodological question we address. While this represents an idealization compared to real landslide sites, it provides a controlled environment for systematically investigating our methodological question.

Importantly, the two key insights from our study are geometry-independent and founded in the fundamental mechanisms of interaction between model parameters and observations: (i) time series data provide better constraints than scalar data, and (ii) parameters are most effectively calibrated by observations that capture their dynamical influence. The idealized setup allows us to demonstrate these insights clearly; researchers can then apply the same framework to their site-specific topographies to identify analogous patterns relevant to their particular cases.

- **Regarding friction parameters:** Yes, the friction parameters are assumed constant over the entire sliding surface. This assumption is widely used in landslide runout modeling, as it captures the bulk behavior of landslides (runout distance, velocity) with a parsimonious model structure. While a complex model with friction parameters varying within the surface would be more physically accurate, it would also be difficult to calibrate. The available observations would not be adequate to constrain them. In summary, while we can formulate advanced models with spatially varying parameters, their efficacy in real-world applications is limited by the availability of adequate observations.

Resulting changes in manuscript

We have added the synthetic topography used in this study as an additional figure. Kindly refer to Section 3.1, (p 18. *Figure 6*).

1.1.3 Comment 3

How did you choose the prior distributions for the friction and discrepancy parameters? They look almost evenly distributed, but not quite. Why?

Response

Thank you for the comment.

- **Regarding the choice of prior:** In this study, we assumed noninformative (uniform) prior distributions for both the friction and discrepancy parameters. Such uniform priors are commonly used in the literature for calibrating landslide runout models. We have included a description of the prior distributions and justified their choice with relevant citations in Section 3.3 (Design of Numerical Experiments).

- **Regarding the apparent unevenness:** This is a visual artifact of histogram binning used for plotting, not a characteristic of the underlying continuous uniform distributions. The priors are truly uniform (flat) over their specified ranges.

Resulting changes in manuscript

Added description of priors used in Section 3.3 (*p.17, lines 391-395*), repeated below for convenience.

In all the 8 experiments we assume uniform priors for the friction parameters. The bounds for the priors are chosen from the literature as mentioned earlier, for $\mu \in [0.02, 0.3]$ and $\xi \in [100, 2200]$ m/s^2 . While such uniform priors are noninformative, they are widely used in literature for calibrating landslide models (Aaron et al., 2019; Navarro et al., 2018; Moretti et al., 2017). Additionally in experiment 7 and 8, we assume an uniform prior for the discrepancy parameters $\sigma_{vel_{TS}}$ and $\sigma_{pos_{TS}}$ with bounds $[1, 5]$ and $[0, 100]$ respectively.

1.1.4 Comment 4

Regarding information gain: KL divergence is just a measure for the dissimilarity of distributions. Its value could be high even though the resulting MAP is far from the true value. So it is a little bit misleading (or optimistic) to call it information gain. The authors need to elaborate a bit why the value of KL divergence alone lets one infer the improvement of the parameter estimation.

Response

Thank you for this comment.

- **Regarding KL divergence as a measure of information gain:** We agree that KL divergence is fundamentally a measure of distributional dissimilarity. However, in Bayesian inference, the KL divergence from posterior to prior has a specific information-theoretic interpretation: it quantifies the reduction in uncertainty about parameters achieved through observing data. This interpretation, where $D_{KL}(P_{\text{posterior}}||P_{\text{prior}})$, represents information gain, is standard in Bayesian optimal experimental design and inverse problems [Huber et al., 2023, Chowdhary et al., 2024]. Higher KL divergence indicates stronger posterior contraction, meaning observations have reduced parameter uncertainty and constitute information gain.
- **Regarding KL divergence alone as measure of improved calibration:** We agree that higher KL divergence alone does not inherently guarantee that posteriors are centered on true parameter values. As you correctly note, one could have high KL divergence with posteriors confidently concentrated around incorrect values, particularly in cases of model misspecification or strongly informative but misplaced priors.

However, the synthetic experimental design used in this study specifically addresses these concerns and validates KL divergence as a measure of calibration performance in our context. First, we generate synthetic observations from the computational model with added noise, eliminating model misspecification. Second, we employ uniform (noninformative) priors over physically plausible parameter ranges, avoiding the risk of strong priors constraining posteriors away from true values. Under these conditions, posterior contraction (quantified by KL divergence) directly reflects movement toward true parameter values, not arbitrary concentration.

This relationship between KL divergence and posterior accuracy is demonstrated empirically in our results. *Table 2* shows that calibration with velocity and position time series yields higher KL divergence values compared to calibration with maximum velocity and final position alone. Examining the corresponding posterior distributions in *Figures 9* and *10* (these were Figures 8 and 9 in the original manuscript), we observe that cases with higher KL divergence exhibit posteriors concentrated around the known true parameter values (indicated by dashed vertical lines). This confirms that in our experimental framework, higher KL divergence reliably indicates greater information gain and improved parameter estimation accuracy.

To summarize, our work follows the information-theoretic interpretation of KL divergence as a measure of information gain and it employs controlled conditions (synthetic data, noninformative priors) under which higher KL divergence reliably signals improved calibration. This framework can be extended by other researchers using synthetic data to systematically analyze how different observations influence parameter estimation in their specific contexts. However, when applying this approach in the presence of model misspecification, KL divergence must be complemented with additional validation methods such as the posterior predictive checks.

Resulting changes in manuscript

To address the reviewer feedback, we have expanded the definition of KL divergence in *Section 2.3* (*p. 9, lines 236-242*) and included two supporting citations.

In the Bayesian setting, KL divergence between the posterior distribution ($P(\theta | y)$) and the prior distribution ($P(\theta)$), as defined in Equation (10), admits a direct interpretation as information gain, since it quantifies the reduction in uncertainty about parameter θ achieved by conditioning on observation y . Higher KL divergence indicates stronger posterior contraction relative to the prior, implying that the observation provides greater information about the parameters; accordingly, we use this quantity as a criterion for data selection, consistent with its standard use in Bayesian optimal experimental design and inverse problems (Marzouk et al., 2007; Huber et al., 2023; Chowdhary et al., 2024).

Additionally we included the limitation on the use of KL divergence as measure of improved parameter calibration in the presence of model misspecification and prior-data conflict, (*p. 29, lines 534-537*).

Second, when model misspecification or prior-data conflict occurs, posteriors can contract away from true parameter values, where higher KL divergence does not necessarily indicate better calibration. When applying this framework in such scenarios, practitioners should therefore complement KL divergence with robust validation methods such as posterior predictive checks.

1.1.5 Comment 5

Almost all axis labels are missing in the figures. Also labels of curves in the legends. This makes reading (and reviewing) the manuscript rather inconvenient since some guess work is involved. This is a major mistake and must be fixed!

Response

Thank you for the comment. We acknowledge that when the manuscript was posted on the preprint server on 02.10.2025, it had rendering issues which resulted in several figures missing axis labels and legends. We apologize for this inconvenience. However as I already posted in the interactive forum as author comment this error was related to rendering issue and not with the submitted manuscript. As soon as we realized this issue on 06.10.2025 we communicated to the editorial office who promptly corrected it the same day. The properly rendered manuscript with all axis labels and legends has been available online since 06.10.2025. We have verified that all figures in the current online version are displayed correctly with complete labeling.

Resulting changes in manuscript

No changes to the manuscript content were necessary. The issue was resolved by correcting the rendering of the existing figures, which now display all axis labels, legends, and annotations as intended.

1.2 Specific comments

1.2.1 Comment 1.43

"parameters'" since rest of sentence is plural.

Response

That is correct. It has been fixed.

Resulting changes in manuscript

The relevant sentence now has been corrected (*p.2 lines 43-44*).

1.2.2 Comment 1.65

better: "uncertainties".

Response

Thank you for the suggestion. We have included it in the revised manuscript.

Resulting changes in manuscript

We have implemented the changes throughout the manuscript and in *Figure 1*.

1.2.3 Comment 1.113

What does "high variance related issues" mean exactly?

Response

Thank you for the comment. In this sentence we are referring to the higher variance of the Monte Carlo-based estimators. Monte Carlo methods yield unbiased estimates of KL divergence but suffer from high variance due to their random sampling nature. Although KL divergence is always a positive quantity, the estimator can produce negative values for individual runs, and many samples are required for the random fluctuations to cancel out and reveal the true KL value.

Resulting changes in manuscript

We have revised the sentence to make the argument more specific and direct (*p.4, lines 112-113*).

1.2.4 Comment 1.162 and 1.164

the equations are not consistent. Exchange y^r and y in eq. (3)?

Response

Thank you for catching that. We have corrected the equation accordingly.

Resulting changes in manuscript

We corrected *Equation 3* (*p.6, lines 163*), to be consistent.

1.2.5 Comment 1.177

why does the appearance of epsilon change? Typo or different meaning? If the latter, explain!

Response

Thank you for catching that. It was a typo and we have corrected it.

Resulting changes in manuscript

We have corrected the typo in *Equation 6* (p.7, lines 182).

1.2.6 Comment 1.210

The operator $\det(\Sigma)$ should not be written in italic.

Response

Thank you for catching that. We fixed it.

Resulting changes in manuscript

We have corrected the typo in *Equation 9* (p.8, lines 216).

1.2.7 Comment 1.218

Better describe MCMC method used. How is stationarity ensured?

Response

Thank you for pointing this out. While the general idea of MCMC sampling is introduced at line 218, the specific implementation details are located in *Section 2.4.2* (p.12-13, lines 306-313).

- **Regarding the MCMC method used:** The specific MCMC algorithm we used was the Affine Invariant Ensemble Sampler (via the Python `emcee` package). This sampler employs multiple chains (walkers) in parallel to efficiently explore the parameter space while remaining invariant to affine transformations of the parameter space, thereby avoiding the need for problem-specific tuning.
- **Regarding the stationarity of the MCMC chains:** Stationarity (convergence to the posterior distribution) was ensured and verified in two ways: (i) Burn-in removal: We discarded the initial 50% of samples as burn-in to eliminate the influence of starting positions; and (ii) Diagnostics: We quantitatively assessed convergence using the Gelman-Rubin statistic (\hat{R}) and autocorrelation time analysis using the `ArviZ` package, in addition to qualitative visual inspection of trace plots.

Resulting changes in manuscript

We expanded the explanation of the convergence of MCMC chains in *Section 2.4.2* (p.13 lines 311-312) to include details on the convergence criteria.

1.2.8 Comment 1.238

What is the structure of \bar{y}^* ? Is it an element of $\{y_1, y_2, \dots, y_n\}$?

Response

Yes, \bar{y}^* belongs to the set of candidate datasets, $\{y_1, y_2, \dots, y_n\}$. Thanks for bringing this to our attention. We realized that the notation related to the observational datasets could be explained better and thus have added the necessary clarification.

Resulting changes in manuscript

Added an explanation regarding the notation of the candidate datasets (*p.10, lines 245-247*).

1.2.9 Comment 1.255

Figure 5 is referenced before Figure 4.

Response

That is correct. We changed the ordering of the figure.

Resulting changes in manuscript

The modified sentence in *p.11, lines 267-269*, correctly refers *Figure 4* before *Figure 5* now.

1.2.10 Comment 1.264

Further explain and justify usage of Gaussian emulator.

Response

Thank you for pointing this out. We agree that both the explanation of the Gaussian process (GP) emulator and the justification of its use required further elaboration. In the revised manuscript, we have therefore expanded *Section 2.4.1* to (i) explain why we chose GP over other surrogate modeling approaches, specifically its ability to provide probabilistic predictions with uncertainty estimates and its superior performance with limited training data; (ii) introduce the mathematical definition of a GP; and (iii) clarify how the GP emulator is incorporated into our Bayesian data selection workflow.

Resulting changes in manuscript

The modified text from *Section 2.4.1* (*p. 11-12, lines 272 - 303 ff.*) is given below.

Surrogate modeling serves as a computational enabler to overcome computational bottlenecks in calculating the KL divergence. As illustrated in Equation (10), calculating KL divergence requires posterior distributions, which are approximated through MCMC sampling (see Section 2.2). The accuracy of this approximation is based on the ability of MCMC chains to effectively explore the posterior space, which typically requires a large number of samples. Each sample necessitates evaluating the likelihood function, entailing one complete execution of the computational model. Therefore, this approach becomes infeasible for computationally expensive models. To tackle this challenge, we employ Gaussian process (GP) emulators, a non-intrusive surrogate modelling technique extensively used for reducing computational costs in Bayesian calibration workflows (Zhao and Kowalski, 2022). The widespread adoption of GP emulators stems from their ability to provide probabilistic predictions, allowing for rigorous quantification of the uncertainty associated with predictions. Furthermore, they offer efficient performance with limited training datasets compared to other machine learning approaches. Mathematically, a GP is defined by a mean function $m(\mathbf{x})$ and a covariance function $k(\mathbf{x}, \mathbf{x}')$ as shown in Equation (13).

$$f(\mathbf{x}) \sim \mathcal{GP}(m(\mathbf{x}), k(\mathbf{x}, \mathbf{x}')) \quad (13)$$

Both the mean and covariance functions in Equation (13) are parameterized by hyperparameters that are inferred from the training data. To implement the GP emulator, we utilize the `emulator` module of PSimPy, which harnesses RobustGaSP, an R package for Gaussian stochastic process emulation that provides robust estimates of the hyperparameters leading to enhanced predictive performance (Gu and Berger, 2016).

Figure 4 illustrates the key steps involved in the surrogate modeling phase. We start by generating a set of input parameters using the `sampler` module of PSimPy, which leverages space-filling schemes like Latin hypercube sampling. Next, we employ the `simulator` module to evaluate our computational model (\mathcal{M}), at these input points. The resulting model outputs are then post-processed according to the emulation strategy determined by the observation dimensionality. For scalar observations, we emulate the parameter-to-observable map, replacing the forward model \mathcal{M} in Equation (9) with a cost-effective surrogate $\hat{\mathcal{M}}$. Alternatively, for high-dimensional observations (e.g., velocity or position time series), we directly emulate the likelihood function, which quantifies the mismatch between model output and observation. This approach leverages the fact that the likelihood is scalar-valued regardless of observation dimensionality, thereby avoiding the computational challenges of constructing GP emulators with high-dimensional outputs. These post-processed outputs, together with the set of input points, constitute our training data used to build and train the GP emulator. We then validate the trained surrogate using k-fold cross-validation. After successful validation, the surrogate model is available for predictions.

1.2.11 Comment 1.270

PsimPy is written in typewriter-like font here but in normal font earlier. Please be consistent.

Response

That is correct. We changed all instances of PSimPy to typewriter font PSimPy to be consistent.

Resulting changes in manuscript

We have corrected the font of PSimPy in all instances.

1.2.12 Comment 1.284

Section 2.4.3 (Data selection) describes the process of computing the KL divergence for all combinations of observations and parameters. However, nothing is written about selecting data (or observations) based on the resulting matrix shown in Fig. 4. This needs to be described.

Response

Thank you for this comment. We agree that the use of the KL-divergence matrix (*Figure 5*) for selecting informative observations can be improved. In the revised manuscript, we have rewritten the paragraph in *Section 2.4.3* to explicitly explain how, for each parameter, the KL-divergence matrix is used to identify and select the most informative observation(s).

Resulting changes in manuscript

The modified text from *Section 2.4.3* (*p.13, lines 319 - 324 ff.*) is given below.

We marginalize the posterior distributions from the Bayesian calibration phase with respect to the parameters and compute KL divergence, as presented in Section 2.3. By calibrating m parameters using n observations, we end up with $n \times m$ KL divergence matrix, as shown in Figure 5, where each entry, $D_{\text{KL}}^{i,j}$, quantifies the information that i^{th} observation y_i provides for calibrating j^{th} parameter θ_j . Using this KL divergence matrix we can identify the most informative observation y_j^* for a given parameter θ_j by maximizing the KL divergence across available observations (as defined in Equation (12)).

1.2.13 Comment 1.316

Subscripts that are not variables or indices should not be italic but normal font (i.e. F_{res}). Furthermore, it is inconvenient to use θ for the angle here, since it is used as variable for the parameters earlier in the manuscript.

Response

Thank you for pointing this. We agree that variables and indices should not be italic and have corrected it. Additionally we agree that the usage of θ for slope angle could be confusing, since it is already used for parameters. Thus we have swapped θ with β to represent slope angle.

Resulting changes in manuscript

We have modified *Equation 14* and *Equation 15* (Equation 13 and Equation 14 in the original manuscript) to make the subscripts non italic and to represent slope angle with β instead of θ .

1.2.14 Comment 1.360

Experiment numbers (1-9) do not match numbers in table.

Response

Thank you for raising this point. We agree that the numbering of experiments in the text was not clearly aligned with the table, which could confuse readers. The confusion arose because *Subsection 4.7* discusses the results of both experiments 7 and 8 together. To address this, we have revised the subsection headings (4.1-4.7) to explicitly indicate which experiment(s) are discussed in each subsection. This provides a clear link between the table, the text, and the results presented.

Resulting changes in manuscript

To address the reviewer feedback we have modified the headings for subsections (4.1-4.7). The modified subsection headings are in *lines 402, 411, 418, 424, 430, 445, 451*.

1.2.15 Comment 1.361

Italic subscripts that are not variables or indices.

Response

We thank the reviewer for this remark and would appreciate further clarification. The relevant passage in the submitted manuscript is:

This section includes results for the curated set of numerical experiments discussed in Section 3.3. We adopt the workflow presented in Section 2.4 and the associated data: (i) Training dataset including set of sampled parameters and the corresponding

In this portion of the text, we could not identify any occurrences of italic subscripts that are non-variables or labels. We have also systematically reviewed and corrected all subscript notation throughout the manuscript. Could you kindly specify which expression at line 361 you are referring to?

1.2.16 Comment 1.364

Figure 6: Some information are missing / not printed (at least in the provided pdf file): legend incomplete (no text next to lines); no axis labels; unit of ξ not printed: Same issues with all the other figures of prior and posterior distributions. When it is unclear which line represents which quantity, it is nearly impossible to estimate the information content and correctness of the figures! This especially difficult for figure 11.

Response

Thank you for identifying these specific missing elements. As noted in our response to General Comment 5, these errors were caused by a PDF rendering error in the initial preprint version. We have verified that in the corrected manuscript, all figures displaying prior and posterior distributions (including *Figures 7 and 12*, which were Figures 6 and 11 in the original manuscript) are now rendered with complete axis labels, legends, and units. We apologize for the difficulty this caused in interpreting the results.

Resulting changes in manuscript

No changes to the manuscript content were necessary. The issue was resolved by correcting the rendering of the existing figures, which now display all axis labels, legends, and annotations as intended.

1.2.17 Comment 1.366

Subscript "max" should not be italic.

Response

Thank you for catching this. We fixed it and corrected all instances of such error.

Resulting changes in manuscript

We have modified the sentence (*p.19, line 403*), such that the subscript "max" is not italic.

1.2.18 Comment 1.368

Are six significant digits for ξ justified here?

Response

Thanks for pointing this out. We have omitted the additional decimal.

Resulting changes in manuscript

The modified sentence(*p.19, lines 405*), now omits the additional decimals for ξ . We made similar correction for ξ in *Table 1*.

1.2.19 Comment 1.372

Where are the KL divergence values given / shown? reference Table 2

Response

Thank you. We have corrected this error.

Resulting changes in manuscript

The modified sentence (*p.19, line 409*), now refers to *Table 2*.

1.2.20 Comment 1.387

"x(t)" here is just text, not typeset as a formula. Please be consistent.

Response

Thanks for catching this, it has been corrected.

Resulting changes in manuscript

We have corrected the typeset error, refer (*p.22, line 424*).

1.2.21 Comment 1.393

Figure 10: axis labels are missing. Are these examples taken from a set of 100 experiments? If so please state that fact. Otherwise the reader wonders how from 6 values you get such a smooth curve in figure 11a.

Response

Thank you for the comment.

- **Regarding missing labels:** As noted in our response to General Comment 5, these errors were caused by a PDF rendering error in the initial preprint version. We have verified that in the corrected manuscript, all figures displaying prior and posterior distributions (including *Figure 11*, which was Figure 10 in original manuscript) are now rendered with complete axis labels, legends, and units. We apologize for the difficulty this caused in interpreting the results.
- **Regarding Figure 10 (*Figure 11* in the revised manuscript):** We agree with your second comment and have added a sentence to explicitly state that the posterior distributions plotted in *Figure 11* (Figure 10 in the original manuscript), are selected from a set of 100 posterior distributions.

Resulting changes in manuscript

To address the reviewers feedback, we have modified the relevant text as (*p.23, lines 430-432*):

We calibrated the friction parameters with 100 different datasets of velocity time series, each containing a varying number of time steps. Seven selected posterior distribution of ξ from these calibrations is depicted in Figure 11, with the y-axis listing the number of velocity time steps used in the calibration.

1.2.22 Comment 1.396

How is it visible that initial time steps have greater information content? That does not become clear. You show graphs for varying numbers of time steps but do not compare different onsets of the time series. Please clarify!

Response

Thank you for this comment. We recognize the ambiguity in our original phrasing. Our experiments used cumulative time windows (0-32, 0-64, ..., 0-1200), all starting from $t=0$. From *Figure 11* (Figure 10 in the original manuscript), we observed that the posterior change when adding early time steps (e.g., from 32 to 64) is considerably larger than when adding later time steps (e.g., from 1100 to 1200). This observation reflects diminishing marginal returns as more data is incorporated, but it does not directly address whether initial time steps inherently contain greater information content.

Your comment prompted us to investigate this question more directly. We performed additional calibration experiments using fixed-length time windows at different temporal positions: (0-100), (100-200), (200-300), (300-400), (700-800), (1000-1100), (1100-1200), and (1200-1300). These experiments directly compare information content across different portions of the time series while controlling for the amount of data used. The results (shown here in Figure 1) clearly demonstrate that posteriors become progressively wider for later time windows, confirming that early time steps contain greater information content than later ones.

Resulting changes in manuscript

Currently we intend to add Figure 1 in supplementary material to support the main narrative without disrupting the flow of the primary results.

1.2.23 Comment 1.399

better: "number of velocity time steps". Otherwise it could be interpreted as KL divergence vs. specific time steps. Same in next sentence on line 400: better "Increasing number of time steps..."

Response

Thanks for your suggestion. We agree with it and have corrected accordingly.

Resulting changes in manuscript

The modified sentence now reads (*p.23, line 437-438*):

Figure 12a, plots the variation of the KL divergence of the posterior and prior distributions of ξ with the number of velocity time steps used for calibration. Increasing number of time steps resulted in higher KL divergence, indicating a positive correlation between the information gain and the number of time steps.

1.2.24 Comment 1.364

Figure 11a: What is the reason for the shape of the KL div curve? Why is there a plateau between 300 and 500 steps and then an increase again?

I suppose figure 11 shows number of time steps used (a) and time steps (b) but that's a guess since x-axis labels are missing. If that is so the start of the plateau corresponds to about 200 steps. It would be interesting to see that length also in figure 10. In figure 10 the three uppermost curves (1000, 1100, 1200 steps) look very similar. In figure 11a, however, the KL divergence is still increasing significantly in that range. Why is that?

Response

Thanks for the comment.

- **Regarding the shape of KL divergence curve:** We are conducting additional simulations to address this comment comprehensively. The results and revised analysis will be included in our resubmission.
- **Regarding Figure 11 (*Figure 12 in the revised manuscript*):** As per your suggestion in comment 399, we have updated the axis label to explicitly denote the number of time steps used for calibration, improving clarity of the temporal scope.
- **Regarding Figure 10 (*Figure 11 in the revised manuscript*):** Following your suggestion, we have added a posterior distribution calibrated with 200 velocity time steps.
- **Regarding the three uppermost curves:** We are conducting additional simulations to address this comment comprehensively. The results and revised analysis will be included in our resubmission.

Resulting changes in manuscript

The axis label in *Figure 12a, in p.24* (Figure 11a in the original manuscript), has been updated to denote the number of time steps. An additional posterior distribution (200 time steps) has been added to *Figure 11, in p.23* (Figure 10 in the original manuscript).

1.2.25 Comment 1.410

Figure 12 is missing axis-labels again. A plot of KL divergence vs. time step would be informative, too. Which time window is used here for the observations?

Response

Thank you for the comment.

- **Regarding missing labels:** As noted in our response to General Comment 5, these errors were caused by a PDF rendering error in the initial preprint version. We have verified that in the corrected manuscript, all figures displaying prior and posterior distributions (including *Figure 13*, which was Figure 12 in the original manuscript) are now rendered with complete axis labels, legends, and units. We apologize for the difficulty this caused in interpreting the results.
- **Regarding KL divergence vs time step size plot:** Figure 11a, in the original manuscript represents a plot of KL divergence vs number of time steps. Could you clarify if you were suggesting a plot of KL divergence vs time step size?
- **Regarding the time window:** In the experiments presented in *Figure 13* (Figure 12 in the original manuscript), the observational datasets consist of the complete velocity time series. We vary the temporal resolution by adjusting the time step size, while using the complete time series.

Resulting changes in manuscript

No changes were necessary in the manuscript.

1.2.26 Comment 1.413/414

you refer to section 2.1 where the discrepancy, i.e. measurement error is called ε . Here you write σ which seems to refer to the STD of applied noise as given in Table 1. Be consistent with naming scheme!

Response

Thank you for pointing out this potential confusion. Both ε and σ are related but refer to different quantities: ε is the discrepancy random variable itself, while σ is the parameter (standard deviation) that characterizes its distribution.

As stated in *Section 2.1* (p.6, lines 166-168), we model the discrepancy ε between measurements y and model predictions $\mathcal{M}(s; \theta)$ as additive Gaussian noise: $\varepsilon \sim \mathcal{N}(0, \Sigma)$, where Σ is the covariance matrix. For scalar observations, this reduces to $\varepsilon \sim \mathcal{N}(0, \sigma^2)$, where σ is the standard deviation. For multiple independent observations, we use $\Sigma = \sigma^2 I$.

In experiments 1-6, we assume σ based on heuristics. In experiments 7-8, we calibrate σ alongside the friction coefficients. Since our synthetic measurements are generated by adding noise with known standard deviation (*Table 1*), successful calibration should recover these noise values, which is confirmed by the posterior distributions in *Figure 14 a-b* (Figure 13 a-b in the original manuscript).

Resulting changes in manuscript

To address the reviewer feedback we have included a clarification on the notation of σ in *Section 2.1.1*, p6, lines 166-172. The modified text is given below.

Typically, the noise is not known, such that we need to assume an ansatz, which constitutes our noise model. The additive Gaussian noise model is one of the most common noise models, where ε is considered to be a realization of a Gaussian distribution, often with zero mean and a covariance matrix Σ , i.e. $\varepsilon \sim \mathcal{N}(0, \Sigma)$. The structure of the covariance matrix depends on the observational dataset we are calibrating. For scalar observations, the covariance matrix reduces to the variance σ^2 . For multidimensional observations, we assume independent errors with constant standard deviation, leading to $\Sigma = \sigma^2 I$. We refer to σ as the discrepancy parameter and in this study, it is either fixed based on heuristic assumptions or calibrated alongside the model parameters.

1.2.27 Comment 1.512

Figure 11b shows the max. acceleration (assuming it is the blue line) at about 200 (no unit given). Figure 10 shows a narrow distribution only for 1000 steps or more. So how do you come to this optimality statement? That does not seem reasonable. There is not even a curve for 200 steps in figure 10.

Response

Thank you for this comment. We agree that the optimality claim requires further clarification.

- **Regarding Figure 11b (*Figure 12b* in the revised manuscript):** The acceleration is represented by the red line, while the blue line corresponds to velocity. The sliding mass reaches its maximum velocity at timestep 134 to be exact.
- **Regarding optimality:** We recognize this term was ambiguous. Our statement refers to the observation window that yields the maximum rate of information gain per time step, not the window that produces the most accurate final calibration (which, as you correctly note from *Figure 11* (Figure 10 in the original manuscript), requires ~ 1000 time steps). Specifically, we observe that the rate of information gain—measured by the slope of the KL divergence in *Figure 12a* (Figure 11a in the original manuscript)—is steepest in the window from $t=0$ to approximately $t=134$, which coincides with the time required for the sliding mass to reach maximum velocity. Similarly, the coefficient of variation for the posteriors drops most sharply in this same window before flattening, as shown here in Figure 2. Furthermore, Figure 1 shows that the (0-100) time window produces the most contracted posterior among all fixed-length windows tested.

Resulting changes in manuscript

We have added clarification regarding the optimality statement in *p.30, line 566*.

2 Changelog of additional manuscript changes

We also report the following notable modifications. Changes are traceable in the attached diff.pdf file.

1. made the usage of abbreviation of Gaussian process (GP) consistent through out the manuscript.
2. swapped the index of observations y with the index of parameters θ to be consistent with the matrix notation in *Figure 5*.
3. non italicized the subscripts through out the manuscript.
4. added additional funding details.

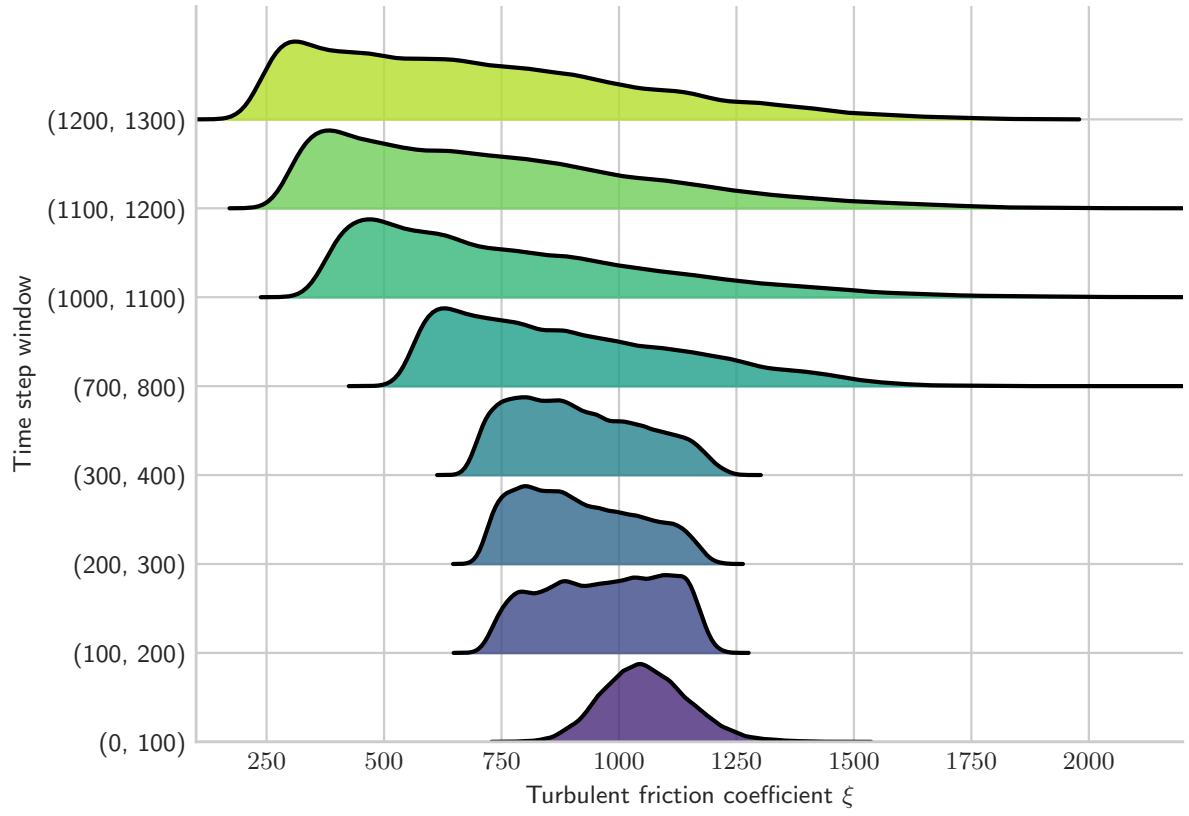


Figure 1: Posterior distributions of turbulent friction coefficient ξ calibrated with a fixed observation window of 100 time steps, with varying onset time. Initial time steps provide the highest information gain.

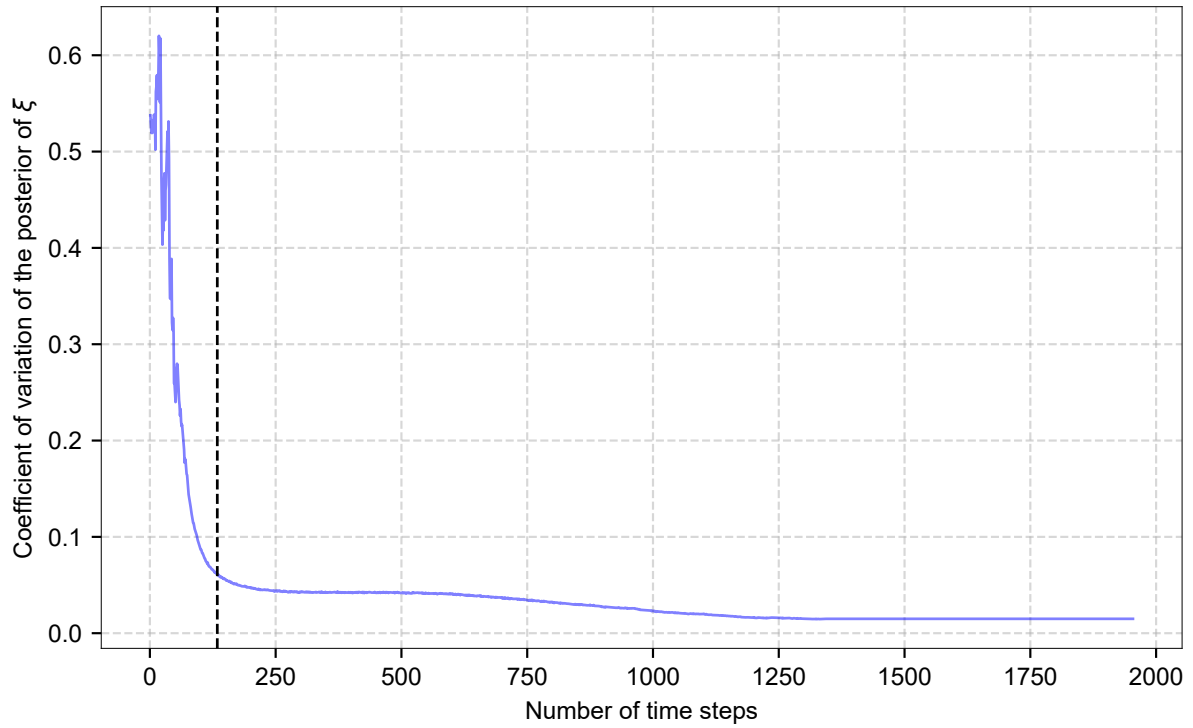


Figure 2: Coefficient of variation (COV) of the posterior distribution of ξ as a function of the number of velocity time steps used for calibration. The COV decreases sharply during the phase when the sliding mass reaches maximum velocity, then plateaus, indicating diminishing posterior contraction as additional observations are assimilated.

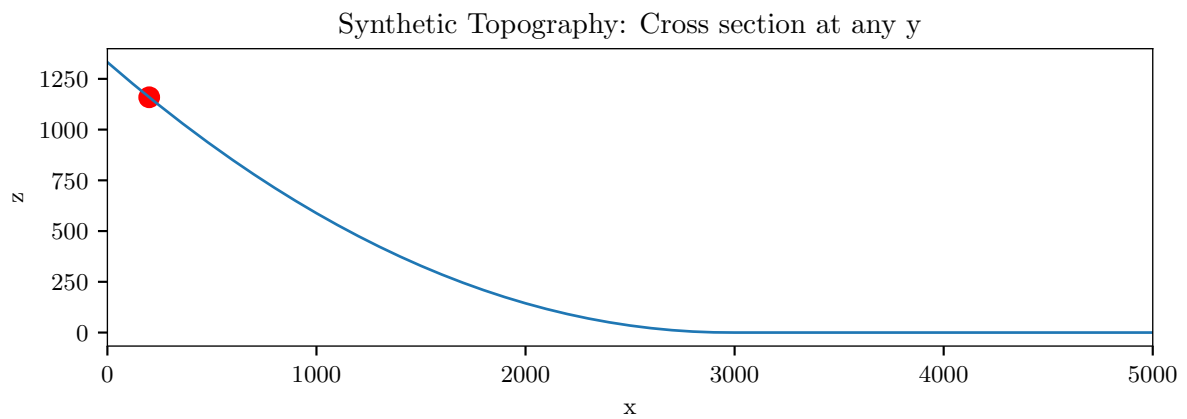


Figure 3: Vertical cross-section of the synthetic topographic model used in this study, with elevation (z) plotted against the horizontal coordinate (x). The topography is constant along the transverse direction. The red marker denotes the position of the initial release point projected onto this cross-section.

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