Multiple-scattering effects on single-wavelength lidar sounding of multi-layered clouds

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Abstract. We performed Monte Carlo simulations of single-wavelength lidar signals from multi-layered clouds with special
10 attention focused on multiple-scattering (MS) effect in regions of the cloud-free molecular atmosphere, i.e. between layers or outside a cloud system. Despite the fact that the strength of lidar signals from molecular atmosphere is much lower compared to the in-cloud intervals, studies of MS effects in such regions are of interest from scientific and practical points of view.

The MS effect on lidar signals is always decreasing with the increasing distance from the cloud far edge. The decreasing is the direct consequence of the fact that the forward peak of particles phase functions is much larger than the receiver field of view
15 (RFOV). Therefore, the photons scattered within the forward peak escape the sampling volume formed by the RFOV, i.e. the escape effect. We demonstrated that the escape effect is an inherent part of MS properties within the free atmosphere beyond the cloud far edge.

In the cases of the ground-based lidar, the MS contribution is lower than 5% within the regions of the cloud-free molecular atmosphere having the distance from the cloud far edge about 1 km or higher. In the cases of the space-borne lidar, the
20 decreasing rate of the MS contribution is so slow that the threshold of 5% can hardly be reached. In addition, the effect of non-uniform beam filling is extremely strong. Therefore, practitioners should employ with proper precautions lidar data from regions below the cloud base when treating data of a space-borne lidar.

In the case of two-layered cloud, the distance of 1 km is sufficiently large so that the scattered photons emerging from the first layer do not affect signals from the second layer when we are dealing with the ground-based lidar. In contrast, signals from
25 the near edge of the second cloud layer are severely affected by the photons emerging from the first layer in the case of a space-borne lidar.

We evaluated the Eloranta model (EM) in extreme conditions and showed its good performance in the cases of ground-based and space-borne lidars. At the same time, we revealed the shortcoming that can affect practical applications of the EM. Namely, values of the key parameters, i.e. the ratios of phase functions in the backscatter direction for the nth-order-scattered photon
30 and a singly scattered photon depend not only on the particles phase function, but also on the distance from a lidar to the cloud and the receiver field of view. Those ratios vary within a quite large range and the MS contribution to lidar signals can be largely overestimated or underestimated if erroneous values of the ratios are assigned to the EM.

1 Introduction

It is well recognized that multiple scattering (MS) inevitably affects data of space-borne lidars (see e.g. Winker, 2003; Young
35 and Vaughan, 2009; Shcherbakov et al., 2022). As for ground-based lidars, the MS relative contribution to lidar signals can
exceed 20 % even in the case of cirrus clouds having the extinction coefficient $\varepsilon_p = 0.2$ km^{-1}, and can reach 200 % when $\varepsilon_p = 1.0$ km^{-1} (Shcherbakov et al., 2022). On the other hand, the MS effect is within measurement errors of ground-based and
airborne lidars, i.e. the single-scattering (SS) approximation can be used, when the receiver field of view (RFOV) is quite
narrow and/or the extinction coefficient is quite low (Shcherbakov et al., 2022).

40 Lidar signals are used as input data to retrieve profiles of characteristics of interest, e.g. the extinction coefficient, the
backscatter coefficient, the lidar ratio (see e.g. Young and Vaughan, 2009). If the MS contribution cannot be neglected, a
solution to the corresponding inverse problem has to take into account the MS effect in order to avoid biased retrievals. To put
it differently, the correction for the effects of multiple scattering has to be applied (Young and Vaughan, 2009).

Generally, any algorithm to solve an inverse problem is based on a solution to the corresponding direct, i.e. forward problem
45 (see e.g. Rodgers, 2000; Neto and Neto, 2013). It is obvious that retrieval quality is closely related to the accuracy of the direct
modelling. To put it in relation to lidar sounding, the quality of the correction for MS effects directly depends on the accuracy
of lidar-signals modelling in multiple-scattering conditions.

Expressed mathematically, any modelling in MS conditions has to be based on the radiative transfer equation and
corresponding boundary conditions (see e.g. Marchuk et al., 2013). It is well known that there exist only a few cases when a
50 solution to the radiative transfer equation can be obtained as an analytical expression. Thus, numerical methods, e.g. Monte
Carlo (MC) simulations (Marchuk et al., 2013) or approximate models are largely applied to obtain solutions. Referring to
lidar sounding, a good review of developed approximate methods and models can be found in (Bissonnette, 2005). Using some
cases as examples, good performance of approximate models was underlined by their authors. At the same time, we believe
that the accuracy level and the applicability bounds of approximate models still need to be rigorously evaluated.

55 It was suggested in the work by Weinman (1968) to approximate a phase function of cloud particles by a somewhat smoothly
varying function of the scattering angle plus a narrow Gaussian peak for small angles. That idea was used to develop models
that simulate lidar signals in multiple-scattering conditions and promising results were obtained (see e.g. Eloranta, 1998;
Hogan, 2006; Hogan, 2008). For example, a good agreement with MC simulations of second-, third-, and fourth-order
scattering was shown for the case of the extinction coefficient of 16.7 km^{-1} (Eloranta, 1998). Moreover, the models (Eloranta,
60 1998; Hogan, 2006; Hogan, 2008) were employed by practitioners to account for MS effects while retrieving clouds' optical
properties on the bases of experimental lidar data (see e.g. Nakoudi et al., 2021; Seifert et al., 2007; Delanoë and Hogan, 2008).
On the other hand, results of MC simulations published in the literature (see e.g. Flesia and Starkov, 1996; Donovan, 2016;
Reverdy et al., 2015; Szczap et al., 2021) evidenced the following. As it is expected, lidar signals from regions of the cloud-
free molecular atmosphere, namely, between cloud layers and/or beyond the far edge of a cloud system, are affected by the
65 scattered light emerging from clouds. To our knowledge, optical processes and cloud characteristics that govern the effect on

lidar signals of the emerging light, i.e. the MS effect, as well as its distinctive features have not been addressed in details in the literature.

The main objective of this work is to perform Monte Carlo simulations of single-wavelength lidar signals from multi-layered clouds with special attention focused on peculiarities of MS effect in regions of the cloud-free molecular atmosphere, i.e. between layers or outside a cloud system. In our opinion, such study helps to obtain further insight into the problem of MS effects. At the same time, it has practical applications because some of inverse-problem algorithms use lidar data taken from the range of the cloud-free atmosphere beyond the far edge of a cloud, for example, the two-way transmittance method (see e.g. Young and Vaughan, 2009; Giannakaki et al., 2007; and references therein).

The second objective of this work is to evaluate performance of an approximate model with the focus on the cloud-free regions. We have chosen for the evaluation the model developed by Eloranta (Eloranta, 1998) because multiple integrals are in its core (see Eq. (11) in (Eloranta, 1998) and Eqs. (3-4) in (Eloranta, 2000)). A code to compute multiple integrals belongs to the domain of basic programming tasks. Therefore, it is an easy matter to develop a code corresponding to the Eloranta model.

Throughout this work, the majority of results are shown and discussed in terms of relative contributions of multiple scattering (see definitions in Section 2.1), that is, multiple-to-single scattering lidar-return ratios (Bissonnette et al., 1995). At the same time, a reader should keep in mind that the ratios show not lidar signals but the relative contribution of MS with respect to lidar signals obtained under the SS approximation. From the point of view of the inverse problem, namely the ratios are of importance because they show the level of retrieval errors if the SS approximation is applied in an inversion algorithm. If different models, which simulate the direct problem, are compared, the ratios evidence clearly the differences between the results (see e.g. Bissonnette et al., 1995). In our opinion, a comparison of lidar signals instead of ratios suffers from a severe disadvantage for the following reasons. Even when lidars signals are corrected for the offset and instrumental factors, they do decrease exponentially because of the extinction. Consequently, the semi-logarithmic plot is usually employed to show data, and even important differences are hardly noticeable in such figures. Moreover, when differences are seen, it is difficult for a reader to estimate their importance from the point of view of the inverse problem.

The MS effect on lidar signals depends on a number of parameters, namely, the configuration (the distance to a cloud, the emitter field of view (EFOV), and the RFOV) as well as the cloud optical characteristics (the extinction coefficient, the albedo, the scattering matrix and so on) (see e.g. Shcherbakov et al., 2022; and references therein). Because the MC method is very time-consuming, it is not suited to take into account variations of all mentioned parameters. Therefore, our study was restricted to the cases when all cloud layers are within the range between the altitudes 8 and 11 km. Almost all MC simulations were performed for cloud particles having the extinction coefficient $\varepsilon_p(h) = 1.0$ km^{-1} for the following reasons. On the one hand, technical capacities of contemporary lidars provide possibility to record signals from the cloud free atmosphere beyond the far edge of a cloud having the optical thickness $\tau_p = 3.0$. On the other hand, MS effect cannot be neglected and is clearly seen in a number of cases (Shcherbakov et al., 2022). Our choice of the parameters values was deliberate despite the fact that the altitude range $H \in [8., 11.]$ km does not correspond to the usual altitudes of warm clouds, the value $\varepsilon_p(h) = 1.0$ km^{-1} is quite

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For brevity sake, the term "sampling volume" is used in this work in reference to the volume bounded by the RFOV of a lidar in the 3D space.

Section 2 addresses methodology of our Monte Carlo simulations in details. Sections 3 and 4 show our simulation results for a ground-based and a space-borne lidars, respectively. Section 5 is devoted to conclusions. Appendix A is focused on the

105   Eloranta model and its input parameters in homogeneous-cloud conditions; Appendix B is devoted to simulation-uncertainty analysis.

2 Methodology

2.1 Background

We use the following notations in this work. The function $S_1(h)$ characterizes lidar signals under the SS approximation

110   (corrected for the offset, instrumental factors, and the two-way ozone transmittance):

$$S_1(h) = [\beta_p(h) + \beta_m(h)] \cdot T^2(h) = [\beta_p(h) + \beta_m(h)] \cdot T_m^2(h) \cdot T_p^2(h), \tag{1}$$

where h is the distance from the lidar; $\beta_p(h)$ and $\beta_m(h)$ represent the backscatter contributions from particles and from the atmospheric molecules; $T^2(h) = T_m^2(h) \cdot T_p^2(h)$ is the two-way transmittance from the lidar to the range h; $T_m^2(h)$ and $T_p^2(h)$ are the molecular and the particulate transmittances, respectively. $T_p^2(h) = 1$ if $h \leq h_b$, where h_b is the distance to the cloud

115   near edge; $T_p^2(h) = \exp[-2\tau_p(h_b, h)]$ when $h \geq h_b$, where $\tau_p(h_b, h) = \int_{h_b}^{h} \varepsilon_p(h')dh'$ is the cloud optical depth, $\varepsilon_p(h)$ is the extinction coefficient of particles.

The notation $S_k(h)$, $k = 2, 3, \dots, n$ represents lidar signals (corrected for the offset, instrumental factors, and the two-way ozone transmittance) when all scattering events from first (single scattering) up to k^{th} inclusive are taken into account; $(k + 1)^{th}$ and higher orders of scattering are neglected. For example, $S_2(h)$ is the double scattering (DS) approximation (see

120   e.g. Bissonnette, 2005). The notation $S_{MS}(h)$ means that all scattering events are taken into consideration. Of course, only $S_{MS}(h)$ can be obtained from real lidar measurements. $S_k(h)$ are useful data of simulations computed with the Monte Carlo method or an approximate model.

We are using below the following characteristics to compare the simulations results

$$R_{kto1}(h) = [S_k(h) - S_{k-1}(h)]/S_1(h), \tag{2}$$

125   $$R_{MSto1}(h) = [S_{MS}(h) - S_1(h)]/S_1(h). \tag{3}$$

The ratio $R_{kto1}(h)$ is the relative contribution of the kth order of scattering to a lidar signal. For example, $R_{4to1}(h) = [S_4(h) - S_3(h)]/S_1(h)$ provides the relative contribution of fourth order of scattering. The ratio $R_{MSto1}(h)$ is the relative contribution of multiple scattering to a lidar signal, i.e., all orders of scattering were taken into consideration. It is evident that

$$R_{MSto1}(h) = \sum_{k=2}^{k=n} R_{kto1}(h), \tag{4}$$

The majority of results of this work are shown and discussed below in terms of ratios $R_{MSto1}(h)$ and $R_{2to1}(h)$.

In order to discuss our results in terms used in the literature (see e.g. Young and Vaughan, 2009; Young et al., 2013; Vaughan et al., 2009; Garnier et al., 2015; and references therein), we employ the following notations and relationships. The "attenuated backscatter", i.e. lidar signals $S_{MS}(h)$ computed in multiple-scattering conditions (corrected for the offset, instrumental factors, and the two-way ozone transmittance) is expressed as (see e.g. Young et al., 2013)

$$S_{MS}(h) = \left[\beta_p(h) + \beta_m(h)\right] \cdot T_m^2(h) \cdot T_{pA}^2(h), \tag{5}$$

where $T_{pA}^2(h) = \exp\left[-2\eta(h_b, h)\tau_p(h_b, h)\right]$ is the apparent particulate two-way transmittance; $\eta(h_b, h)$ is the multiple scattering function (see Appendix in Shcherbakov et al. (2022) for details), i.e. a parameterization describing the effect of MS on particulate extinction (Young et al., 2013).

$$S_m(h) = \left[\beta_m(h)\right] \cdot T_m^2(h) \tag{6}$$

is a lidar signal computed under the condition of the free molecular atmosphere using available meteorological data (see e.g. Winker et al., 2009).

The scattering ratio $\mathcal{R}(h) = \left[\beta_p(h) + \beta_m(h)\right]/\beta_m(h) = \left[\beta_p(h)/\beta_m(h)\right] + 1$ is a useful parameter to work with lidar data; $\mathcal{R}(h) = 1$ for the molecular atmosphere. The attenuated scattering ratio can be defined as (see e.g. Winker et al., 2009)

$$\mathcal{R}'_{MS}(h) = S_{MS}(h)/S_m(h) = \mathcal{R}(h) \cdot T_{pA}^2(h). \tag{7}$$

The definitions of a MS lidar signal $S_{MS}(h)$ with Eq. (5), of a SS lidar signal $S_1(h)$ with Eq. (1), and of the attenuated scattering ratio with Eq. (7) lead to the following properties for intervals of the cloud-free molecular atmosphere

$$\mathcal{R}'_{MS}(h) = T_{pA}^2, \tag{8}$$

$$S_1(h) = \left[\beta_m(h)\right] \cdot T_m^2(h) \cdot T_p^2 = S_m(h) \cdot T_p^2, \tag{9}$$

$$S_{MS}(h) = \left[\beta_m(h)\right] \cdot T_m^2(h) \cdot T_{pA}^2 = S_m(h) \cdot T_{pA}^2, \tag{10}$$

where $T_p^2 = T_{pA}^2 = 1$ when $h < h_b$; $T_p^2 = const$ and $T_{pA}^2 = const$ when $h > h_{end}$, where h_{end} is the distance to the cloud far edge.

It follows from the relationships above that

$$R_{MSto1}(h) = 0, \mathcal{R}'_{MS}(h) = 1, \tag{11}$$

when $h < h_b$, and

$$R_{MSto1}(h) = \left(T_{pA}^2/T_p^2\right) - 1 = const, \mathcal{R}'_{MS}(h) = T_{pA}^2 = const. \tag{12}$$

when $h > h_{end}$.

In addition, the following relationship can be useful for interpretation of Monte Carlo data

$$\mathcal{R}'_{MS}(h) = \left[R_{MSto1}(h) + 1\right] \cdot T_p^2 = const \text{ when } h > h_{end}. \tag{13}$$

160 It should be underlined that, if measurement errors are neglected, the functions $R_{MSto1}(h)$ and $\mathcal{R}'_{MS}(h)$ are expected to be constant when we are dealing within the intervals of the cloud free molecular atmosphere, i.e. either $h < h_b$ or $h > h_{end}$. Moreover, the apparent optical thickness $\eta \cdot \tau_p(h_b, h_{end})$ of the cloud can be easily computed (see e.g. Garnier et al., 2015)

$$\eta \cdot \tau_p(h_b, h_{end}) = -0.5 \cdot ln[\mathcal{R}'_{MS}(h_2)/\mathcal{R}'_{MS}(h_1)] \tag{14}$$

where h_1 and h_2 can be any points satisfying the conditions $h_1 < h_b$ and $h_2 > h_{end}$.

2.2 Simulation software and conditions

Our tool to perform Monte Carlo simulations of lidar signals was the McRALI (Monte Carlo Radar Lidar) software developed at the Laboratoire de Météorologie Physique (Szczap et al., 2021; Alkasem et al., 2017). The software employs a forward Monte Carlo (MC) approach along with the locate estimates method to simulate propagation of radiation (see e.g. Marchuk et al., 2013). McRALI is based on the 3DMCPOL model (Cornet et al., 2010). The polarization state of the radiation is computed

170 using Stokes vectors and scattering matrices of atmospheric compounds. It takes into account molecular scattering. In this work, the properties of the atmosphere were assigned according to the 1976 standard atmosphere (NOAA, 1976). McRALI is a fully 3D software, that is, values of the extinction coefficients, the single scattering albedos, and the scattering matrixes are assigned in 3D-space. Moreover, the mixture of different types of aerosols and/or clouds is allowed. The position of a lidar can be anywhere within or outside of the atmosphere, that is, space-borne, airborne, and ground-based measurement conditions

175 can be simulated. A user can assign a lidar beam direction, a receiver field-of-view (RFOV), and a Stokes vector and a divergence of the emitted light. McRALI software was thoroughly tested against data available in the literature (see Appendix in Alkasem et al., 2017). We perfume tests when new data are published (under the condition that a paper provides all input data necessary to reproduce simulations). For example, we obtained very good agreement with Fig. 4 of the work by Wang et al. (2021) (including the linear and the circular polarization degree). The good agreement is with data for both ground-based

180 and space-borne lidars.

In this work, MC data were computed so that photons were integrated over the range gate 20 m; i.e. they correspond to photon counting mode. Such small value of the range gate was chosen with the aim to study multiple scattering in details regardless of the fact that it does not correspond to real lidar systems. In other words, the spatial resolution of our MC data is 20 m. The orders of scattering up to 20 were considered in MC simulations to compute the total multiple scattering. (We have verified

185 that the difference between data obtained with 20 and 10 orders of scattering was not statistically significant for the simulations conditions of this work.)

The results of this work are complementary to the data of the work by Shcherbakov et al. (2022) since most of our MC simulations were performed for the cases of (*i*) the same water cloud and (*ii*) the same jet-stream cirrus cloud. The corresponding normalized phase function $f_W(\theta)$ and $f_{JSC}(\theta)$, where θ is scattering angle, are shown in Fig. 1 by blue and

190 black curves, respectively; their behaviour at forward and backward angles can be seen in the insets. The scattering matrix of water cloud was computed according to the Mie theory for water spheres having the gamma size distribution with the effective

diameter $d_{eff} = 18.0$ µm (the standard deviation of 5.3 µm). The SS characteristics of cirrus cloud were computed using the Improved Geometric Optics Method (Yang and Liou, 1996); the size distribution of particles was taken to be the gamma distribution with $d_{eff} = 56.8$ µm (the standard deviation 20.1 µm).

195 To gain a better understanding of the set of parameters that govern MS effect we will use artificial phase functions. We will use the term "chimerical" for them to underline that they are not expected to fit a real phase function, but to reproduce some of its characteristics. A chimerical phase function is a sum of three Gaussian functions $G_i(\theta), i = 1,2,3$: a narrow peak $G_1(\theta)$ for scattering angles close to 0° (forward direction), a somewhat smoothly varying function $G_2(\theta)$, and a peak $G_3(\pi - \theta)$ for angles close to 180°. (We use the notation "$\pi - \theta$" in order to underline that we are dealing with the peak at the backward

200 direction). The first two component are in accord with the work by Weinman (1968). The third component is inspired by the results of the work (Zhou and Yang, 2015) where rigorous numerical simulations based on solving Maxwell's equations showed that a backscattering peak exists even in cases of randomly oriented ice crystals. We use the formula $G_i(\theta) = a_i \cdot exp[-(\theta^2)/(\theta_{s,i}^2)]$ to define the Gaussian components $G_i(\theta)$, where $\theta_{s,i}$ is the $1/e$ angular half-width. The utility of a chimerical phase function consists in the possibility to vary one of parameters whereas other characteristics remain unchanged.

205 The first chimerical phase function $f_{Ch1}(\theta) = \sum_{i=1}^{3} G_i(\theta)$ is shown by the red curve in Fig. 1. It was designed to meet the following properties of the normalized phase function $f_W(\theta)$ of the water cloud. $f_{Ch1}(0) = f_W(0)$, $f_{Ch1}(\pi) = f_W(\pi)$, and the both phase functions have the same value of the lidar ratio. The width of the Gaussian component $G_1(\theta)$ of $f_{Ch1}(\theta)$ is assigned so that the function $f_{Ch1}(\theta)\sin(\theta)$ has the maximum at the same value $\theta_{max} = 10.82$ mrad as the function $f_W(\theta)\sin(\theta)$ has. The width of $G_3(\pi - \theta)$ was adjusted so that $f_{Ch1}(\theta)$ and $f_W(\theta)$ lead to coincident functions $R_{2to1}(h)$ (see Section 3.1). The

210 width of Gaussian component $G_2(\theta)$ is large; it assures that sufficient proportion of photons is scattered sideward. The chimerical phase function $f_{Ch2}(\theta)$ is shown by the green curve in Fig. 1. It has the same components $G_1(\theta)$ and $G_2(\theta)$ as $f_{Ch1}(\theta)$. The only difference is $G_3(\pi - \theta)$, which is larger by a factor of 15. Consequently, the curves of $f_{Ch1}(\theta)$ and $f_{Ch2}(\theta)$ coincide in Fig. 1 till the scattering angle about 170°. The values of parameters a_i and $\theta_{s,i}$ of the chimerical phase functions are given in Table 1.

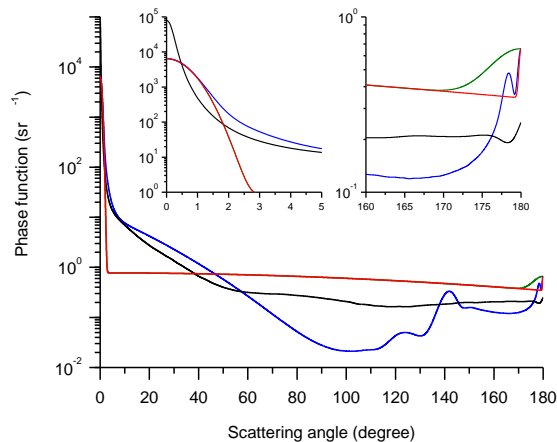



Figure 1. Normalized phase functions: water cloud – blue lines, jet-stream cirrus – black lines, chimerical phase function $f_{Ch1}(\theta)$ – red lines, chimerical phase function $f_{Ch2}(\theta)$ – green lines.

Table 1. Values of the input parameters of the chimerical phase functions.

	a_1	a_2	a_3	$\theta_{s,1}$ (degree)	$\theta_{s,2}$ (degree)	$\theta_{s,3}$ (degree)
$f_{Ch1}(\theta)$	2.2690	0.062	4.086E-05	0.88	200.0	0.327
$f_{Ch2}(\theta)$	2.2712	0.062	6.26045E-04	0.88	200.0	5.0

220 Along with MC data we provide the results, which we obtained using our codes based on the Eloranta model (EM) (Eloranta, 1998) (see details in Appendix A). In what follows the data of our simulations using the EM are referred as "multiple scattering" or are labelled as "MS" when up to 5 orders of scattering were considered. The contribution of the fifth order is sufficiently small in all cases considered below. The addition of the sixth order increases unreasonably the time of computing with the EM.

225 In this work, each cloud layer is plane-parallel (unless otherwise stated) and homogeneous; all scattering matrixes were assigned with an angular resolution of 0.01° (about 0.175 mrad); the emitter wavelength λ is 0.532 μm.

3 Ground-based lidar

The results of this section were obtained for a ground-based lidar, which is at the altitude $H = 0$ km, and the distance to the clouds base is 8 km. The full receiver field-of-view (RFOV) is 1.0 mrad (except Figs. 3c and 3d); the full emitter field-of-view

230 (EFOV) is 0.14 mrad. The emitter wavelength λ is 0.532 μm. (We used the characteristics of the lidar system that is in operation at Clermont-Ferrand (Freville et al., 2015).) In order to assure good statistical quality of our Monte Carlo modelling, each signal was simulated with $2 \cdot 10^{11}$ photons emitted by the lidar (with $4 \cdot 10^{11}$ photons for the cirrus clouds). Simulations

of signals were performed for the orders of scattering $n = 1$ (single scattering), $n = 2$ (double scattering), and multiple scattering with n equal 20.

3.1 Single-layer cloud

The single-layer cloud is within the altitude range $H \in [8., 11.]$ km, that is, has the optical thickness $\tau_p = 3.0$ (the extinction coefficient $\varepsilon_p = 1.0$ km^{-1}). Black and red points in Fig. 2 show the results of our MC simulations reported in terms of the ratios $R_{MSto1}(d)$ and $R_{2to1}(d)$, respectively. The parameter d is the distance measured from the cloud base, i.e. the cloud is within the range $d \in [0., 3.]$ km. The interval $d \in]3., 6.]$ km is the cloud-free molecular atmosphere, i.e. $H \in]11., 14.]$ km. Figures 2a and 2b correspond to the water and cirrus cloud, respectively. The relative contributions $R_{MSto1}(d)$ and $R_{2to1}(d)$ computed using the EM are shown in Fig. 2 by the green and blue curves, respectively. The MC in-cloud data, i.e. $d \in [0., 3.]$ km, were reported and discussed in the work (Shcherbakov et al., 2022). The focus of interest for this work is the cloud-free molecular atmosphere, that is, the interval $d \in]3., 6.]$ km.

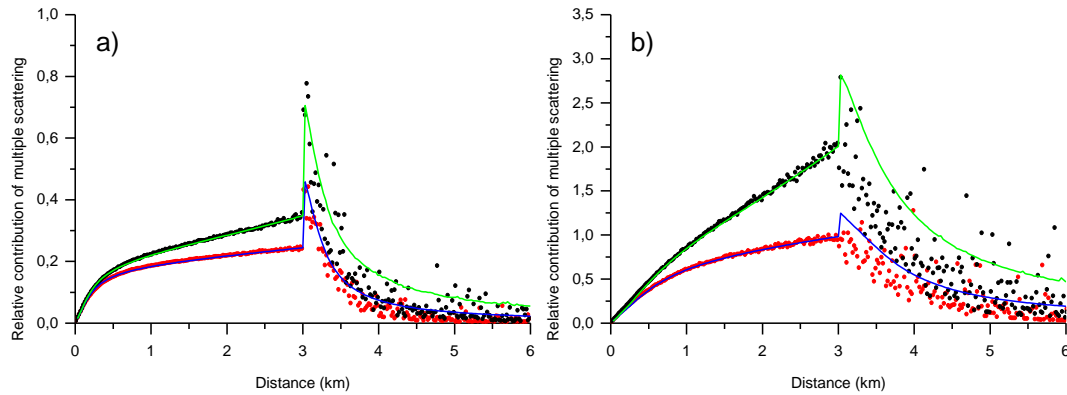



Figure 2. Monte Carlo simulations of multiple scattering R_{MSto1} (black points) and double scattering R_{2to1} (red points) relative contributions to lidar signals; (a) water cloud, (b) jet-stream cirrus. Eloranta-model simulations are shown by the green (MS) and the blue (double scattering) curves.

Our MC simulations reveal the following features. The function $R_{MSto1}(d)$ and $R_{2to1}(d)$ have undergone a stepwise jump immediately beyond the cloud far edge. It should be kept in mind that lidar signals $S_1(h)$, $S_2(h)$, and $S_{MS}(h)$ sharply decrease immediately beyond the cloud far edge (see e.g. Fig. 7 below). The decreasing of $S_1(h)$ is faster, therefore the ratios $R_{MSto1}(d)$ and $R_{2to1}(d)$ have undergone a stepwise jump. After the jump, the ratios decrease and tend to zero. It should be noted that the stepwise jump with subsequent decreasing were already reported in the work (Flesia and Starkov, 1996), where multiple

scattering to a space-borne lidar return from clear molecular atmosphere obscured by transparent upper-level crystal clouds

255 was assessed by the use of the Monte Carlo technique.

It is seen in Figs. 2a and b that the EM is able to well simulate $R_{MSto1}(d)$ and $R_{2to1}(d)$ within the cloud layer $d \in [0., 3.]$ km. The simulation results can be considered as acceptable in the range $d \in]3., 6.]$ km. That is, our EM data show the stepwise jump of the same amplitude as the MC data immediately beyond the cloud far edge. In contrast, the decreasing rate of $R_{MSto1}(d)$ and $R_{2to1}(d)$ is lower. Therefore, the EM slightly overestimates the multiple scattering contribution in the cloud-

260 free molecular atmosphere. We achieved the good agreement with the MC data by adjusting the EM parameters only for the interval $d \in [0., 3.]$ km (see details and the definition of parameters in Appendix A). We have not succeeded to improve the fitting quality for the range $d \in]3., 6.]$ km by varying the fraction $\gamma(h)$ of the energy in the forward peak of the phase function. Thus, all EM data of this work were obtained with $\gamma(h) = 1/2$. The key fact is that the fittings of the water cloud case were obtained using values of the ratios $\mathcal{P}_n(\pi, h)/\mathcal{P}_1(\pi, h)$, $n = 2, ..., 5$ about 0.5 or lower (see discussion in Appendix A). As for

265 the cloud-free molecular atmosphere, the ratios $\mathcal{P}_n(\pi, h)/\mathcal{P}_1(\pi, h)$ are "equal to 1.0 due to the broad nature of the molecular phase function near the backscatter direction" (Eloranta, 1998; Whiteman et al., 2001).

3.1.1 Stepwise jump and escape effect

It is of importance to underline that the discussion in this Section is mainly based on the data obtained under conditions of the double scattering (DS) approximation. Namely, the ratio $R_{2to1}(d)$ of the water cloud case is used as the base to explain the

270 stepwise jump and the escape effect for the following reasons. The both effects are well pronounced in the data $R_{2to1}(d)$ in Fig. 2a, the DS accounts for more than 2/3 of the multiple scattering, and last but not least, the DS can be understood intuitively. The properties of $R_{2to1}(d)$, i.e. of double scattering, within the interval $d \in]3., 6.]$ km cannot be due to the stretching of the pulse length. The definition and a good explanation of the pulse stretching can be found in (Miller and Stephens, 1999). The simplified explanation could be as follows. In the case of double scattering, a photon goes through two scattering within the

275 cloud, returns to the receiver and has the round-trip distance equal to the case of the single scattering from the range of the free atmosphere beyond the cloud far edge. The maximal round-trip distance depends on the configuration geometry, i.e. on the distance from the lidar to the cloud, the cloud depth, the EFOV, and the RFOV. In the case of Fig. 2, the EFOV and the RFOV are narrow whereas the distance from the lidar to particles of the cloud layer is quite short. The round-trip distance of a double-scattered photon can gain a few meters in such conditions. It means that only the range $d \in]3., 3.02]$ km of $R_{2to1}(d)$ can be

280 somewhat affected by the pulse-length stretching. (See Fig. S1 and the explanation in the Supplement.) In addition, we have to underline the following. The EM uses the assumption that "the multiply scattered photons are scattered from the same slab as the single-scattered photons" (see p. 2466 in Eloranta (1998)). To put it differently, the EM ignores the pulse stretching. Nevertheless, it reproduces with good accuracy the stepwise jumps in Fig. 2 on the base of the phase functions parameters. Therefore, it is safe to assume that the stepwise jump of $R_{MSto1}(d)$ and $R_{2to1}(d)$ is due to the stepwise jump in phase-function

285 properties at angles close to 180° (between the phase function of particles within the cloud and the Rayleigh scattering within the free atmosphere).

That assumption is confirmed by the plots in Figs. 3a and b, where the results of MC simulations are shown as the ratios $R_{MSto1}(d)$ and $R_{2to1}(d)$ for the cases of the chimerical phase functions $f_{Ch1}(\theta)$ and $f_{Ch2}(\theta)$, respectively. We adjusted the width of the component $G_3(\pi - \theta)$ of $f_{Ch1}(\theta)$ so that MC simulations with $f_{Ch1}(\theta)$ give the same $R_{2to1}(d)$ within the range

290 $d \in [0., 3.]$ km as $R_{2to1}(d)$ of the water cloud in Fig. 2a. It turns out that the peak at the backward direction of the water cloud is a little bit larger than $G_3(\pi - \theta)$ of $f_{Ch1}(\theta)$ (see Fig. 1). Nevertheless, the MC data in Fig. 3a are coincident with the MC data in Fig. 2a for the ratios $R_{MSto1}(d)$ and $R_{2to1}(d)$ within the full range $d \in [0., 6.]$ km. The good agreement is due to the fact that one of the key parameters of multiple scattering is a weighted average of a phase function near the backscatter direction (see Eq. (10) of Eloranta, 1998). (See Fig. S2 and the intuitive explanation in the Supplement.) That average depends on

295 properties of the forward and backward peaks of the phase function as well as the receiver field of view. It means that we fitted the value of the weighted average when we adjusted the width of the Gaussian function $G_3(\pi - \theta)$.

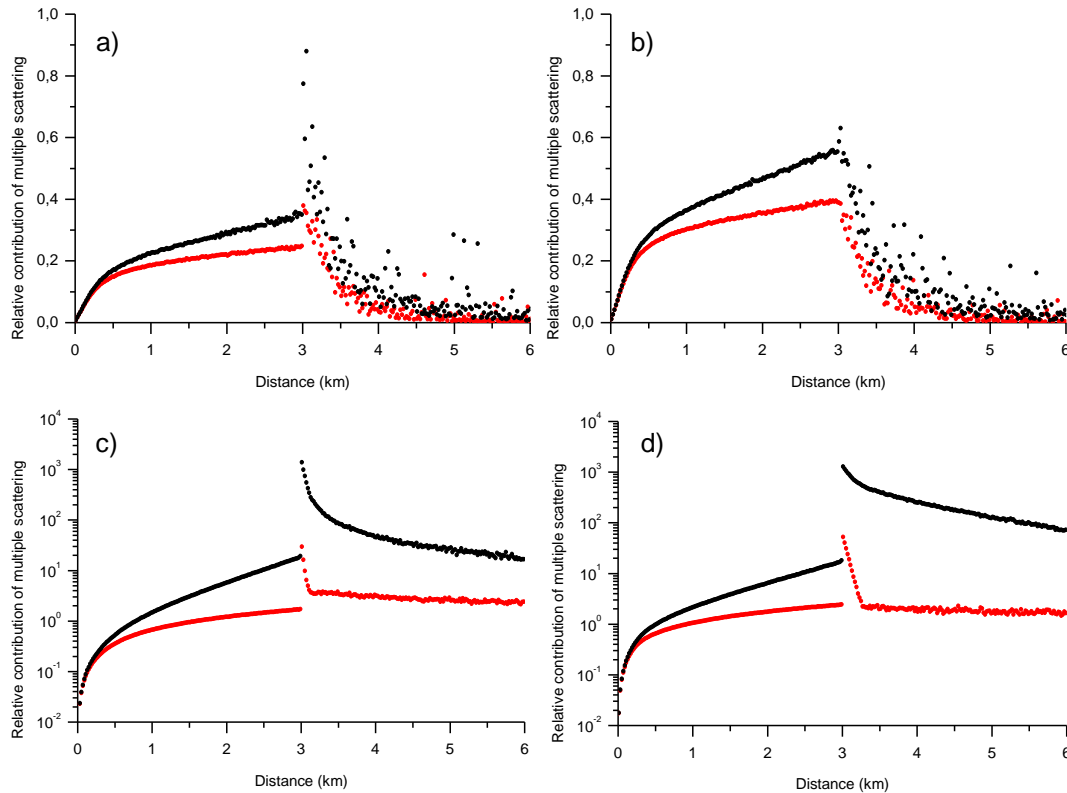



Figure 3. Monte Carlo simulations of multiple scattering R_{MSto1} (black points) and double scattering R_{2to1} (red points) relative contributions to lidar signals; (a) and (b) RFOV=1 mrad; (c) and (d) RFOV=110 mrad; (a) chimerical phase function $f_{Ch1}(\theta)$; (b) and (d) chimerical phase function $f_{Ch2}(\theta)$; (c) water cloud.

The chimerical phase functions $f_{Ch1}(\theta)$ and $f_{Ch2}(\theta)$ have the same values of the parameters $\theta_{s,1}$ and $\theta_{s,2}$, but the width $\theta_{s,3}$ is 15 times higher for $f_{Ch2}(\theta)$. That leads to marked distinctions in the ratios $R_{MSto1}(d)$ and $R_{2to1}(d)$ (see Fig. 3b). There is no a stepwise jump immediately beyond the cloud far edge. It means that the component $G_3(\pi - \theta)$ of $f_{Ch2}(\theta)$ is large enough to have the weighted average equal to $f_{Ch2}(\pi)$ as in the case of the Rayleigh phase function. If we use the terms of the Eloranta model (Eloranta, 1998), the ratio $\mathcal{P}_2(\pi, h)/\mathcal{P}_1(\pi, h) = 1$ for the phase function $f_{Ch2}(\theta)$, i.e. it has the same value as in the case of the Rayleigh phase function. To put it differently, a higher proportion of photons is scattered by the cloud in the backward direction within the RFOV and contribute to lidar signals in the MS case and under the DS approximation. As a consequence, the ratios $R_{MSto1}(d)$ and $R_{2to1}(d)$ of Fig. 3b are much higher than in Figs. 2a and 3a for the in-cloud range $d \in [0., 3.]$ km.

The MC data of Figs. 2a, 3a, and 3b are coincident within the interval of the cloud-free molecular atmosphere $d \in]3., 6.]$ km if they are superimposed in a same figure. Thus, it is safe to assume that two following properties are defined by the forward-peak width of the phase function and the RFOV: (i) the proportion of scattered photons emerging from a cloud and subsequently scattered in the backward direction to the receiver, and (ii) the decreasing rate of the relative contribution of multiple scattering outside the cloud. (We recall that we are dealing with a ground-based lidar, the cloud optical-thickness is not high, and the RFOV and the EFOV are narrow.) That assumption explains the difference in the decreasing rates within the range $d \in [3., 6.]$ km between Figs. 2a and 2b. The forward peak of the scattering phase function of the cirrus cloud is much stronger compared to that one of the water cloud. That leads to the slower decreasing rate.

In our opinion, those properties are a direct consequence of the fact that the photons scattered within the forward peak escape the sampling volume. (For simplicity sake, we will use the term "escape effect" to refer to that phenomenon.) The following arguments justify that statement. Let us consider the case of the forward scattering. If we refer to Fraunhofer diffraction by large spheres (see e.g. Ch. 8.3 of Van de Hulst, 1981), the first dark ring, i.e. the Airy disk, is at the angle $\theta_{Airy} \approx 36$ mrad (about 2 degrees) when a particle has the diameter 18 μm and the wavelength λ is 0.532 μm. $\theta_{Airy} \gg$ RFOV/2 = 0.5 mrad. If we refer to the phase function of the water cloud (see Fig. 1), the intervals of angles [0., 0.5] mrad and [0., 36.] mrad account for 0.059% and 41.3% of the total scattered light, respectively. In such conditions, it can be hardly expected that a large proportion of small angle forward-scattered photons always remain within the field of view of the detector; more likely photons escape the sampling volume.

With the aim of confirming our arguments, we performed MC simulations for the cases of larger RFOVs. All but the RFOV parameters of lidar configuration and the water cloud properties are the same as in the case of Fig. 2a. The full RFOV is 110 mrad. Such large value assures that the narrow peak $G_1(\theta)$ (forward direction) of the chimerical phase functions is totally

within the angle RFOV/2 = 55 mrad (about 3 degrees). Black and red points in Fig. 3c and d show the results of our MC simulations reported in terms of the ratios $R_{MSto1}(d)$ and $R_{2to1}(d)$, respectively. Figures 3c and 3d show the cases of the water cloud and the chimerical phase function $f_{Ch2}(\theta)$, respectively. (Note the log scale of the y-axis in Figs. 3c and d.)

It is seen that the ratios $R_{2to1}(d)$ have undergone a very strong stepwise-jump immediately beyond the cloud far edge. If we consider the configuration geometry, i.e. the angle RFOV/2 = 55 mrad and the distance from the lidar to the cloud far edge of 11 km, the pulse stretching is the cause of the jump. The pulse stretching strongly affects $R_{2to1}(d)$ in Fig. 3d within the range $d \in]3., 3.25]$ km. The ratio $R_{2to1}(d)$ is almost constant within the interval $d \in [3.25, 6.]$ km. (In our opinion, the slight decreasing is due to the pulse-stretching effect.) The properties of the ratio $R_{2to1}(d)$ in Fig. 3c are the same but less pronounced. We can hypothesize that photons that were forward scattered within angles > 3 degrees play noticeable role in the case of the water cloud. The results shown in Figs. 3c and 3d mean that only when the RFOV is sufficiently large, small angle forward-scattered photons remain within the field of view of the detector and the escape effect is eliminated. As for the cases of multiple scattering, the ratios $R_{MSto1}(d)$ in Figs. 3c and 3d are very high due to the large RFOV and the escape effect is evident.

It is seen that the decreasing due to the escape effect is an inherent part of $R_{MSto1}(d)$ properties within the free atmosphere beyond the cloud far edge. That property is in direct contradiction with Eqs. (10 -14) above, which are the consequences of Eq. (5). Therefore, we can conclude that Eq. (5) is an approximate model of lidar signals under MS conditions because it does not take into account the escape effect.

3.1.2 Practical aspects

Knowing that the value of the extinction coefficient $\varepsilon_p = 1.0$ km⁻¹ is not typical of cirrus clouds, we provide practitioners with estimations of MS effects for lower values of ε_p of the jet-stream cirrus. Black points in Fig. 4 show the results of our MC simulations reported in terms of the ratio $R_{MSto1}(d)$. The parameter d is the distance measured from the cloud base, i.e. the cloud is within the range $d \in [0., 3.]$ km. The interval $d \in]3., 6.]$ km is the cloud-free molecular atmosphere, i.e. the altitude $H \in]11., 14.]$ km. The MC simulations were performed for the same geometry of plane-parallel homogeneous cloud as in the case of Fig. 2b. The only difference consists in the values of the extinction coefficient, which were $\varepsilon_p = 0.06$ and $\varepsilon_p = 0.2$ km⁻¹ in Figs. 4a and 4b, respectively. It is seen that the lidar data are affected by MS within the cloud ($d \in [0., 3.]$ km) and above the cloud far edge ($d \in]3., 6.]$ km). The cases of Fig. 4 are characterized by the quite low values of the extinction coefficient, i.e. the low probability of the interaction of a photon with cloud particles. Moreover, the RFOV, i.e. the sampling volume, and the forward peak of the scattering phase function are narrow. All that led to the rather high dispersion of the MC data in Fig. 4 despite the very high number $4 \cdot 10^{11}$ of sampled photons. Nevertheless, it is safe to conclude that the MS contribution is decreasing with the distance from the cloud for edge due to the escape effect. The MS contribution is lower than 5% within the regions of the cloud-free molecular atmosphere having the distance from the cloud far edge about 1 km or higher when $\varepsilon_p \leq 0.2$ km⁻¹.

Table 2 shows the values of the apparent optical thickness $\eta \cdot \tau_p(h_b, h_{end})$ of the cloud computed using Eq. (14) with two values of h_2 assigned within the interval $d \in]3., 6.]$ km (the altitude $H \in]11., 14.]$ km). The values 0.2 and 3.0 km mean the distance from the cloud far edge within the cloud-free molecular atmosphere, they correspond to $d = 3.2$ ($H = 11.2$) and $d = 6.0$ ($H = 14.0$) km, respectively. It is seen that the computed value of the apparent optical thickness depends on the chosen value of h_2. It is close to the value of the real optical thickness when $h_2 = 14.0$ km and can be about 15% lower when $h_2 = 11.2$ km in the cases of the jet-stream cirrus.

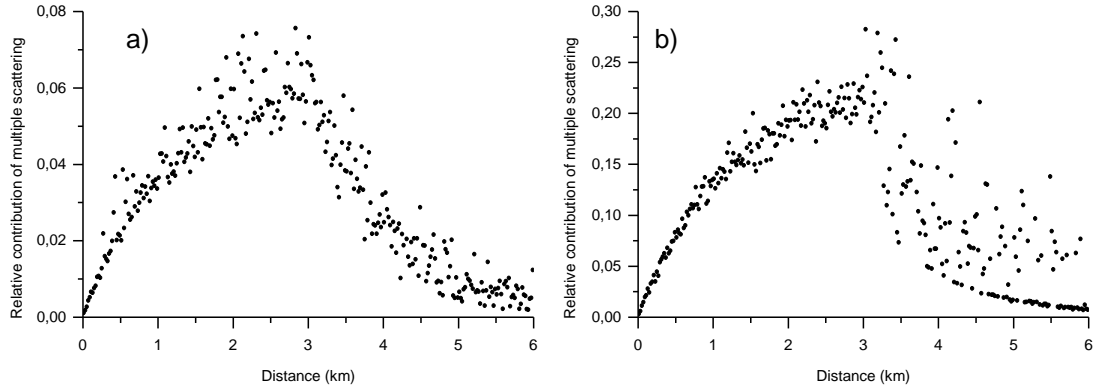



Figure 4. Monte Carlo simulations of multiple scattering relative contributions R_{MSto1} to lidar signals from the jet-stream cirrus; the extinction coefficient is (a) 0.06 km^{-1} and (b) 0.2 km^{-1}.

Table 2. Estimated values of the apparent optical thickness $\eta \cdot \tau_p(h_b, h_{end})$.

MC data case (figure)	Distance from cloud (km)	Apparent optical thickness 0.2	Apparent optical thickness 3.0	Real optical thickness
Water cloud	(Fig. 2a)	2.83	2.99	3.0
Jet-stream cirrus	(Fig. 2b)	2.58	2.94	3.0
Jet-stream cirrus	(Fig. 4a)	0.15	0.18	0.18
Jet-stream cirrus	(Fig. 4b)	0.51	0.60	0.60

 3.2 Two-layered cloud

The two-layered cloud consists of homogeneous layers situated at the altitudes from 8 to 9 km and from 10 to 11 km. Every layer has the optical thickness $\tau_p = 1.0$; the total optical thickness is $\tau_p = 2.0$. The black and red points in Fig. 5 show the results of our MC simulations reported in terms of the ratios $R_{MSto1}(d)$ and $R_{2to1}(d)$, respectively. The parameter d is the distance measured from the cloud base, i.e. the layers are within the ranges $d \in [0., 1.]$ and $d \in [2., 3.]$ km. The intervals $d \in]1.,$ 2.[and $d \in]3., 6.]$ km are the cloud-free molecular atmosphere. Figures 5a and 5b correspond to the water and cirrus cloud, respectively. The relative contributions $R_{MSto1}(d)$ and $R_{2to1}(d)$ computed using the EM are shown in Fig. 5 by green and blue lines, respectively.

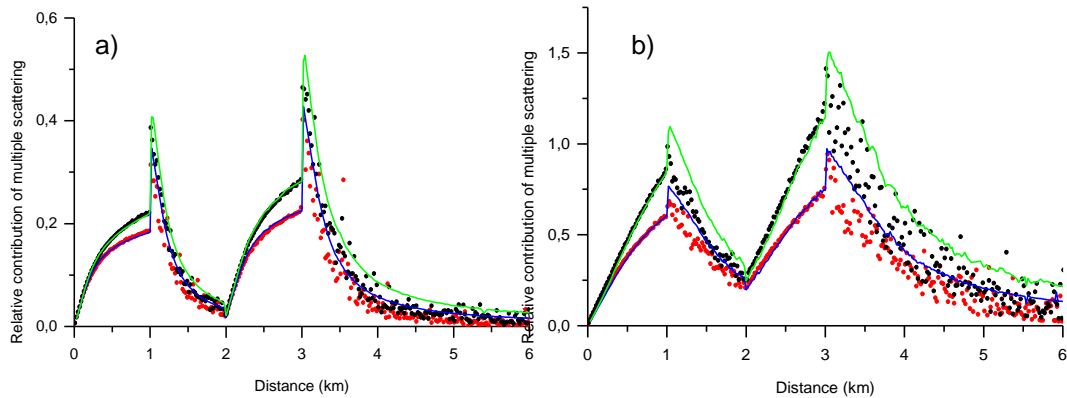



Figure 5. Monte Carlo simulations of multiple scattering R_{MSto1} (black points) and double scattering R_{2to1} (red points) relative contributions to lidar signals; (a) water cloud, (b) jet-stream cirrus. Eloranta-model simulations are green (MS) and blue (double scattering) curves.

The features of the MC data within the intervals of the cloud-free molecular atmosphere are closely similar to those addressed in the previous section. In addition, the following property is noteworthy. The decreasing rate of the MS relative contributions in the case of the water cloud is quite fast and therefore scattered photons emerging from the first layer almost do not affect the lidar signal from the second layer. (The values of the ratios $R_{MSto1}(d = 2.0)$ and $R_{2to1}(d = 2.0)$ are close to zero.) As it was discussed above, the decreasing rate of the MS relative contributions in the case of the cirrus clouds is much slower compared to the water clouds. Therefore, scattered photons emerging from the first layer affect the lidar signal from the second layer so that the ratios $R_{MSto1}(d = 2.0)$ and $R_{2to1}(d = 2.0)$ are about 0.25. In other words, the lidar signal from the near edge of the second layer is about 25 % higher compared to the SS approximation. Obviously, the distance between cloud layers is a key parameter. The values of the ratios $R_{MSto1}(d)$ and $R_{2to1}(d)$ at the near edge of the second layer vary if that distance changes.

As for our EM simulations, we used the same values of the ratios $\mathcal{P}_n(\pi, h)/\mathcal{P}_1(\pi, h)$, $n = 2, ..., 5$ as in the previous section for each cloud layer. We can conclude another time that the EM is able to well simulate MS contributions within the cloud layers. As for the intervals of the cloud-free molecular atmosphere, the behavior of $R_{MSto1}(d)$ and $R_{2to1}(d)$ is correct whereas the MS contribution is slightly overestimated.

4 Space-borne lidar

The results of this section were obtained for a space-borne lidar, which is at the altitude $H = 705$ km. The full receiver field-of-view (RFOV) is 0.13 mrad; the full emitter field-of-view (EFOV) is 0.1 mrad. The emitter wavelength λ is 0.532 µm. Those values correspond to the technical characteristics of the Cloud-Aerosol Lidar with Orthogonal Polarization (CALIOP) (Young and Vaughan, 2009). In order to assure good statistical quality of our Monte Carlo modelling, each signal was simulated with $2 \cdot 10^{11}$ photons emitted by the lidar (with $4 \cdot 10^{11}$ photons for the cirrus clouds). Simulations of signals were performed for the orders of scattering $n = 1$ (single scattering), $n = 2$ (double scattering), and multiple scattering with n equal 20.

4.1 Single-layer cloud

4.1.1 Plane-parallel homogeneous cloud

The single-layer cloud is within the altitude range $H \in [8., 11.]$ km and has the optical thickness $\tau_p = 3.0$ (the extinction coefficient $\varepsilon_p(h) = 1.0$ km^{-1}). For reasons of direct comparison of our data with those ones addressed in the literature, we show our simulated signals of the space-borne lidar in Fig. 6. The SS $S_1(h)$ and MS $S_{MS}(h)$ lidar signals are shown by the blue and black points, respectively. Qualitatively, Figs. 6a and 6b are similar to Figs. B1c and B1d, respectively, of the work Reverdy et al. (2015), as well as to Figs.1c and 1d of the work by Donovan (2016). The distinction in the quantitative characteristics is due to the difference in the cloud optical thickness and optical parameters of the particles. The feature that the MS signals below the cloud base tend to the SS signals is well pronounced. Multiple scattering ratios $R_{MSto1}(d)$ are more suitable to quantify that feature compared to lidar signals shown in the semi-logarithmic plot.

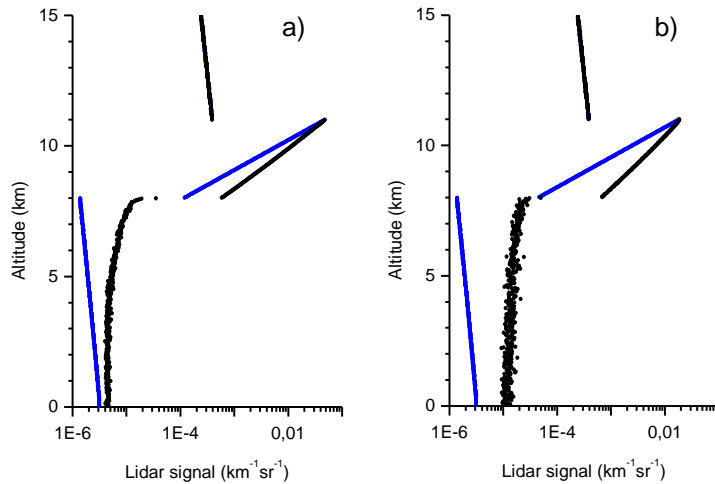



Figure 6. Monte Carlo simulations of single scattering (blue points) and multiple scattering (black points) lidar signals; (a) water cloud, (b) jet-stream cirrus.

Black and red points in Fig. 7 show the results of our MC simulations reported in terms of the ratios $R_{MSto1}(d)$ and $R_{2to1}(d)$, respectively. The parameter d is the distance measured from the cloud near edge from the lidar, i.e. the cloud is within the range $d \in [0., 3.]$ km. ($d = 0.$ km corresponds to the altitude $H = 11.$ km.) The interval $d \in]3., 11.]$ km (the altitude H from 8. to 0. km) is the cloud-free molecular atmosphere below the cloud. Figures 7a and 7b correspond to the water and cirrus cloud, respectively. The relative contributions $R_{MSto1}(d)$ and $R_{2to1}(d)$ computed using the EM are shown in Fig. 7 by the green and blue curves, respectively. The MC in-cloud data, i.e. $d \in [0., 3.]$ km, were reported and discussed in the work (Shcherbakov et al., 2022). The focus of interest for this work is the cloud-free molecular atmosphere, that is, the interval $d \in]3., 11.]$ km.

The features of the MC data within the range of the cloud-free molecular atmosphere have much in common with those addressed in Section 3.1. In addition, the following properties are noteworthy. In the case of the space-borne lidar, the difference between values of $R_{MSto1}(d)$ and $R_{2to1}(d)$ is much larger compared to Figs. 2a and b, that is, the third and higher orders of scattering dominate. The escape effect does affect the lidar signals. At the same time, the decreasing rate of $R_{MSto1}(d)$ and $R_{2to1}(d)$ is much slower. The distance 8 km from the cloud is not sufficient to reach the conditions of the SS approximation. That result is of importance for practitioners, who work with data of space-borne lidars, because the estimated value of the apparent optical thickness depends on the distance from the cloud far edge chosen as the reference point h_2 (see details in Section 4.1.3).

440 As in the cases of the ground-based lidar, the EM is able to simulate well MS contributions within the cloud layers. We employed the same approach to obtain values of the ratios $\mathcal{P}_n(\pi, h)/\mathcal{P}_1(\pi, h)$, $n = 2, \ldots, 5$ as in Section 3.1 (see Appendix A for details). As in the cases of the ground-based lidar, the fittings of the water cloud case were obtained using values of the ratios $\mathcal{P}_n(\pi, h)/\mathcal{P}_1(\pi, h)$, $n = 2, \ldots, 5$ about 0.5 or lower. The behavior of $R_{MSto1}(d)$ and $R_{2to1}(d)$ is correct within the range of the cloud-free molecular atmosphere, whereas the MS contribution is slightly overestimated. It is seen that the EM is not

445 able to reproduce the amplitude of the stepwise jump of $R_{MSto1}(d)$ immediately beyond the cloud far edge. Thus, the stepwise jump in those cases is not only due to the stepwise jump in phase-function properties for angles close to 180°. We can suggest that the range $d \in]3., 3.1]$ km is somewhat affected by the pulse stretching.

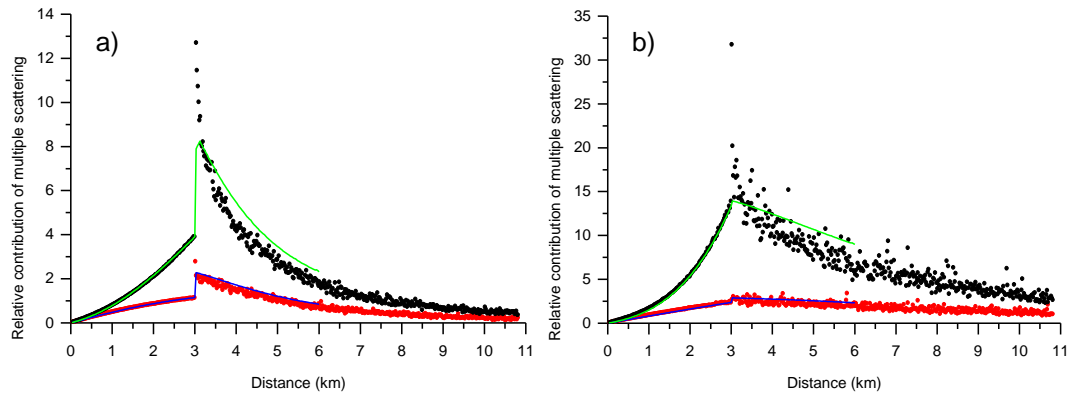



Figure 7. Monte Carlo simulations of multiple scattering R_{MSto1} (black points) and double scattering R_{2to1} (red points)
450 relative contributions to lidar signals; (a) water cloud, (b) jet-stream cirrus. Eloranta-model simulations are green (MS) and blue (double scattering) curves.

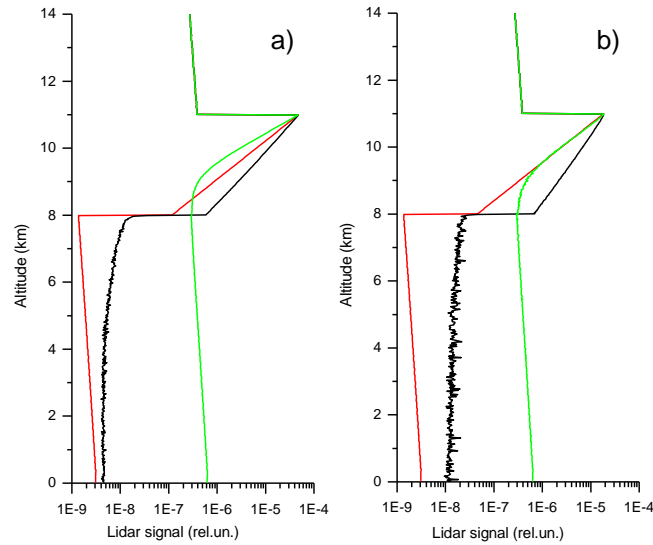
4.1.2 Non-uniform beam filling

Another problem associated with a reference range taken below the cloud base consists in the following. Space-borne lidars such as CALIOP have a quite large laser footprint, so that a cloud field can be horizontally heterogeneous within the footprint.
455 That raises the well-known problem of non-uniform beam filling (NUBF). Some effects of the NUBF on lidar data within cloud fields were addressed in works (Szczap et al., 2021; Alkasem et al., 2017). The lidar signals from the cloud-free atmosphere below cloud base are affected as well.

In order to understand some basic properties under 3D multiple-scattering conditions, we performed simulations for the case of a very simple 3D field. (All data of this subsection were obtained using the McRALI software, i.e. the Monte Carlo method.)
460 A homogeneous cloud covers half of the field as viewed from the top. The centre of CALIOP laser footprint is exactly on the cloud border. In other words, one half of the laser beam passes through the cloud, and the other half goes through the molecular-

atmosphere. The thickness of the cloud is 3 km and the cloud top altitude is 11 km. The extinction coefficient of particles of the cloud is 2 km^{-1}. To put it differently, we have chosen the value of the extinction coefficient so that the amount of particles within the volume bounded by the EFOV in the 3D case is exactly the same as in the case of the plane-parallel homogeneous cloud. The same is true if we consider the sampling volume. Therefore, the optical thickness of the 3D cloud, when averaged over the EFOV, is $3. = (0. + 6.)/2$.

The NUBF effect is so high in such conditions that it has to be shown in terms of lidar signals. Figure 8 is complementary to Fig. 7, i.e. it shows the results based on the same MC simulations but as lidar signals. Figures 8a and 8b correspond to the water and cirrus cloud, respectively. The black and red lines are lidar signals (corrected for the offset and instrumental factors) obtained with the Monte Carlo method in MS conditions and the SS approximation, respectively. We recall that the black and red lines were obtained for the case of the homogeneous plane-parallel cloud having the optical thickness $\tau_p = 3.0$.

The green lines in Fig. 8 are the lidar signals computed in the case of the 3D cloud field in MS conditions. Within the in cloud altitudes $H \in [8., 11.]$ km, they are lower than the MS signals from the corresponding homogeneous cloud (the black lines), which is in total agreement with the theory (see Ch. 3.1 in (Alkasem et al., 2017)). As for the range below the cloud base, it is seen that the NUBF makes the situation much more aggravated. The lidar signals (the green curves) are around 200 times higher compared to the SS approximation for the homogeneous plane-parallel cloud (the red curves). That is the direct consequence of the fact that in the 3D case one half of the laser beam passes through the molecular atmosphere whereas another half passes through the cloud having $2\tau_p = 6$.

480 **Figure 8.** Monte Carlo simulations of lidar signals. Homogeneous plane-parallel cloud: (*i*) black curves correspond to multiple scattering and (*ii*) red curves correspond to single scattering conditions; green curves correspond to multiple scattering for 3D cloud field; (a) water cloud, (b) jet-stream cirrus.

4.1.3 Practical aspects

Knowing that the value of the extinction coefficient $\varepsilon_p = 1.0$ km^{-1} is not typical of cirrus clouds, we provide practitioners with
485 estimations of the escape and NUBF effects for lower values of ε_p of the jet-stream cirrus. The black points in Fig. 9 show the values of the MS relative contributions $R_{MSto1}(d)$ (see Eq. 3) in the case of the homogeneous plane-parallel cloud. The MC simulations were performed for the same geometry of plane-parallel homogeneous cloud as in the case of Fig. 7b. The only difference consists in the values of the extinction coefficient, which were $\varepsilon_p = 0.06$ and $\varepsilon_p = 0.2$ km^{-1} in Figs. 9a and 9b, respectively. It is seen that the lidar data are affected by MS within the cloud ($d \in [0., 3.]$ km) and below cloud base ($d \in]3.,$
490 11.] km).

NUBF effects are shown by the red points in Fig. 9. As previously, (*i*) a homogeneous cloud covers half of the field as viewed from the top; (*ii*) the centre of CALIOP laser footprint is exactly on the cloud border; (*iii*) the value of ε_p is by a factor of 2 higher than the extinction coefficient of the corresponding plane-parallel cloud. The values of the extinction coefficient of the 3D cloud, when averaged over the EFOV, are $0.06 = (0. + 0.12)/2$ and $0.2 = (0. + 0.4)/2$ in the cases of Figs. 9a and 9b,
495 respectively. The relative difference

$$R_{NUBFto1}(h) = [S_{NUBF}(h) - S_1(h)]/S_1(h). \tag{15}$$

is taken to be a measure of the NUBF effects, where $S_{NUBF}(h)$ is the MS lidar signal simulated using the Monte Carlo method in the case of the 3D cloud field; $S_1(h)$ is the lidar signal computed in the case of the corresponding plane-parallel cloud under the SS approximation. In other words, the parameter $R_{NUBFto1}$ is devoted to show the relative contribution of the MS and the
500 NUBF taken together.

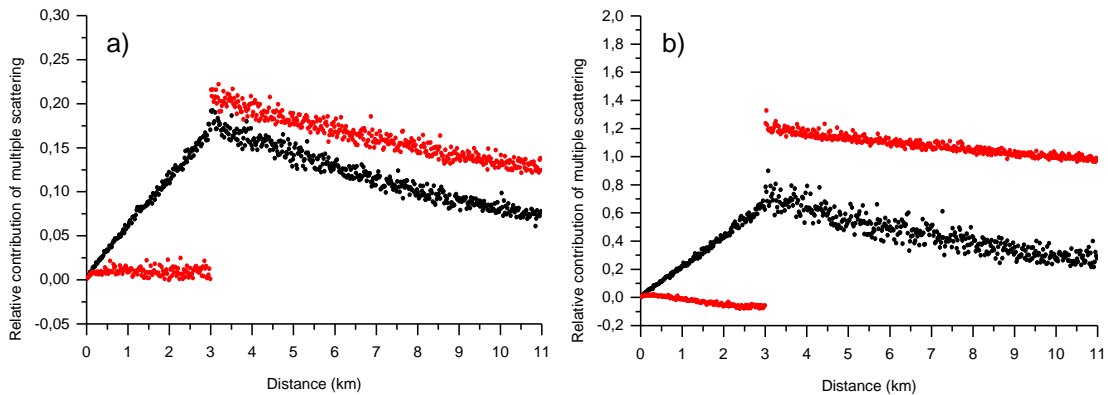



Figure 9. Monte Carlo simulations of multiple scattering effects (jet-stream cirrus). Black points are the relative contributions R_{MSto1} to lidar signals from a homogeneous plane-parallel cloud; red points are the relative contributions $R_{NUBFto1}$ of the MS and the NUBF to lidar signals from a 3D cloud; the extinction coefficient is (a) 0.06 km^{-1} and (b) 0.2 km^{-1}.

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Another time it is seen that the MS effect is somewhat weakened by the NUBF within the cloud range ($d \in [0., 3.]$ km). When the optical thickness within the cirrus cloud is quite low, MS lidar signals from a 3D cloud are fairly close to the SS lidar signals from the corresponding plane-parallel homogeneous cloud (see Figs. 9 and 8b). That property is not valid in the case of the water cloud (see Fig. 8a). It can be hypothesized that more photons escape through the cloud side when the forward-

510 scattering peak of particles is larger.

As for lidar signals within the range of the free atmosphere below cloud base ($d \in]3., 11.]$ km), they are always affected either by the multiple scattering or by the non-uniform beam filling. There is no interval where the MS effect is lower than 5%. And, the NUBF effect on lidar signals is always higher than the MS effect in the case of plane-parallel cloud. We recall that our comparison is done under the condition that the amount of particles within the volume bounded by the EFOV in the 3D case

515 is exactly the same as in the case of the plane-parallel homogeneous cloud.

Table 3. Estimated values of the apparent optical thickness $\eta \cdot \tau_p(h_b, h_{end})$. The real optical thickness of 3D clouds is the value averaged over the EFOV.

Distance from cloud (km) / MC data case (figure)		Apparent optical thickness		Real optical thickness
		0.2	7.98	
Water cloud	(Fig. 7a)	1.91	2.81	3.0
Jet-stream cirrus	(Fig. 7b)	1.60	2.36	3.0
Water cloud (3D)	(Fig. 8a)	0.32	0.35	3.0
Jet-stream cirrus (3D)	(Fig. 8b)	0.31	0.34	3.0
Jet-stream cirrus	(Fig. 9a)	0.10	0.14	0.18
Jet-stream cirrus (3D)	(Fig. 9a)	0.09	0.12	0.18
Jet-stream cirrus	(Fig. 9b)	0.34	0.48	0.60
Jet-stream cirrus (3D)	(Fig. 9b)	0.21	0.26	0.60

520 The escape effect is noteworthy as well. It is seen that $R_{MSto1}(d)$ and $R_{NUBFto1}(d)$ are decreasing with the increasing distance from the cloud base in all four cases of Fig. 9. Examples of its consequences in terms of the apparent optical thickness of the cloud $\eta \cdot \tau_p(h_b, h_{end})$ are given in Table 3. The data were computed using Eq. (14) with two values of h_2 assigned within the

interval $d \in]3., 11.]$ km (the altitude $H \in]8., 0.]$ km). The values 0.2 and 7.98 km mean the distance from the cloud far edge within the cloud-free molecular atmosphere, they correspond to $d = 3.2$ ($H = 7.8$) and $d = 10.98$ ($H = 0.02$) km, respectively. It is seen that the estimated values of $\eta \cdot \tau_p(h_b, h_{end})$ are always lower than the values of the real optical thickness, they are much lower in the cases of the 3D cloud (NUBF) compared to the plane-parallel cloud, and they strongly depend on the assigned value of h_2.

As in the case of the ground-based lidar, we can conclude that Eq. (5) does not take into account the escape effect. Therefore, it is only an approximate model of MS signals from space-based lidars.

4.2 Two-layered cloud

The two-layered cloud is the same as in Section 3.2, that is, two homogeneous layers are at the altitudes from 8 to 9 km and from 10 to 11 km. Every layer has the optical thickness $\tau_p = 1.0$; the total optical thickness is $\tau_p = 2.0$. Black and red points in Fig. 10 show the results of our MC simulations reported in terms of the ratios $R_{MSto1}(d)$ and $R_{2to1}(d)$, respectively. The parameter d is the distance measured from the cloud near edge, i.e. $d = 0.$ km corresponds to the altitude $H = 11.$ km. The cloud layers are within the ranges $d \in [0., 1.]$ and $d \in [2., 3.]$ km. The intervals $d \in]1., 2.[$ and $d \in]3., 11.]$ km (the altitudes H from 10. to 9. km and from 8. to 0. km) are the cloud-free molecular atmosphere. Figures 10a and 10b correspond to the water and cirrus cloud, respectively.

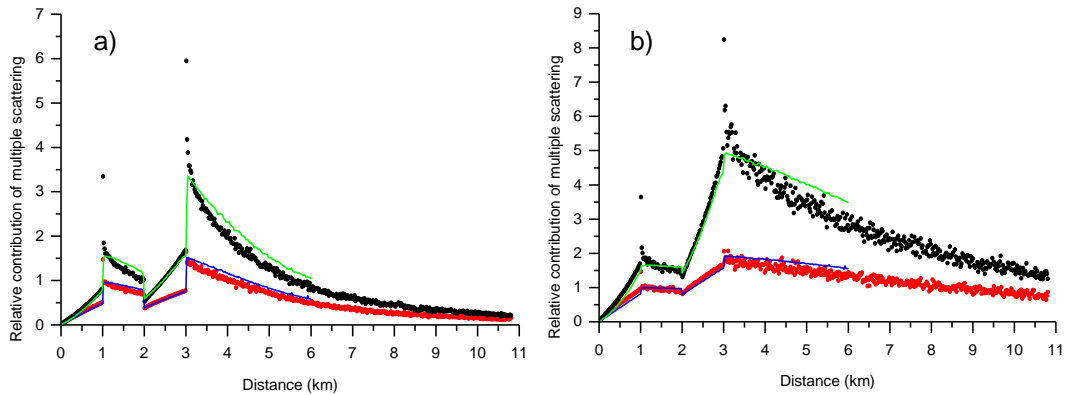



Figure 10. Monte Carlo simulations of multiple scattering R_{MSto1} (black points) and double scattering R_{2to1} (red points) relative contributions to lidar signals; (a) water cloud, (b) jet-stream cirrus. Eloranta-model simulations are green (MS) and blue (double scattering) curves.

The main properties of our MC simulations in Fig. 10 are in agreement with the results of the work (Flesia and Starkov, 1996); the distinctions are due to differences in the phase functions and the configuration characteristics. In addition, the vertical resolution in our work is 7.5 times better, and therefore the ratios $R_{MSto1}(d)$ and $R_{2to1}(d)$ are seen in more details.

The general behaviour of MC data around $d = 1.$ km and within the range $d \geq 3.$ km in Fig. 10 is the same as it is within the range $d \geq 3.$ km in Fig. 7. Thus, we focus attention only on the interval around $d = 2.$ km, that is, on the near edge of the second cloud layer. The difference between the cases of the ground-based and the space-borne lidars is better seen from comparison of Figs. 5a and 9a, i.e. the water clouds. In the case of the space-borne lidar, the sampling volume is so large (due to the large receiver footprint) that the majority of forward scattered photons remain within it. This leads to the value $R_{MSto1}(d = 2.0 \, km)$, which is almost the same as $R_{MSto1}(d = 1.0 \, km)$ (see Fig. 9a). In contrast, the sampling volume, i.e. the footprint, is narrow in the case of the ground-based lidar. The majority of forward scattered photons escape it when they are going through the cloud-free molecular atmosphere within the interval $d \in]1.,2.[$ km. This leads to the value $R_{MSto1}(d = 2.0 \, km)$ close to zero (see Fig. 5a). Generally, the same features are observed in Figs. 5b and 9b. They are less pronounced because the forward scattering pick of the phase function of cirrus cloud is much narrower.

The relative contributions $R_{MSto1}(d)$ and $R_{2to1}(d)$ computed using the EM are shown in Fig. 9 by green and blue curves, respectively. The simulations were performed with the same values of the ratios $\mathcal{P}_n(\pi, h)/\mathcal{P}_1(\pi, h)$, $n = 2, \dots, 5$ as in Section 4.1.1. Generally, the EM curves follow well the MC results. It is seen another time that the EM slightly overestimates the MS contribution in the cloud-free intervals and it is not able to reproduce the effect related to the pulse stretching.

5 Conclusions

We performed Monte Carlo simulations of single-wavelength lidar signals from multi-layered clouds with special attention focused on features of multiple-scattering (MS) effect in regions of the cloud-free molecular atmosphere, i.e. between layers or outside a cloud system. Despite the fact that the strength of lidar signals from molecular atmosphere is much lower compared to the in-cloud intervals, studies of MS effects in such regions are of interest from scientific and practical points of view. The results of this work are shown and discussed in terms of relative contributions of multiple scattering, that is, multiple-to-single scattering lidar-return ratios $R_{MSto1}(d)$. That provides possibility to accentuate the visibility of MS effects.

The scattered photons emerging from a cloud do affect lidar signals received from the intervals of the cloud-free molecular atmosphere. The MS effect is rather high within the region that is close to the far edge of a cloud. Those high values of the ratios $R_{MSto1}(d)$ are due to the features of the molecular backscattering, i.e. to the fact that the ratios $\mathcal{P}_n(\pi, h)/\mathcal{P}_1(\pi, h)$ are "equal to 1.0 due to the broad nature of the molecular phase function near the backscatter direction" (Whiteman et al., 2001; Eloranta, 1998). In the cases of the space-borne lidar, the additional MS contribution is due to the pulse stretching.

The MS effect on lidar signals is decreasing with the increasing distance from the cloud far edge, i.e. the ratio $R_{MSto1}(d)$ tends to zero. The decreasing is the direct consequence of the fact that the forward peak of particles phase functions is much larger than the receiver field of view. Therefore, the photons scattered within the forward peak escape the sampling volume formed

by the RFOV, i.e. the escape effect. The escape effect is an inherent part of MS properties within the free atmosphere beyond the cloud far edge. That property is in direct contradiction with Eq. (5). Consequently, Eq. (5) is an approximate model of lidar signals under MS conditions.

The two-way transmittance method (see, e.g. Young and Vaughan, 2009; Giannakaki et al. 2007) is based on Eq. (5) and used to deduce values of the apparent optical thickness of clouds. In view of the results of this work, it is advisable at least to choose the reference point always at the same distance from the cloud far edge when estimating the apparent optical thickness of clouds.

In the cases of the ground-based lidar, the MS contribution is lower than 5% within the regions of the cloud-free molecular atmosphere having the distance from the cloud far edge about 1 km or higher. Therefore, it is safe to say that practitioners can use those regions as a reference and estimate the real optical thickness of clouds (see e.g. (Giannakaki et al. 2007) and references therein), if the EFOV and the RFOV are not very large. In the cases of the space-borne lidar, the decreasing rate of the MS contribution is so slow that the threshold of 5% can hardly be reached.

Using an example of a very simple 3D field, we demonstrated that the effect of non-uniform beam filling can be extremely strong in the case of a space-borne lidar. It is so strong, that, in our opinion, practitioners should employ with proper precautions lidar data from regions below the cloud base when treating data of a space-borne lidar. At the same time, it should be underlined that effects of the NUBF need further study, which will provide statistically significant results.

In the case of two-layered cloud, the distance of 1 km is sufficiently large so that the scattered photons emerging from the first layer do not affect signals from the second layer when we are dealing with the ground-based lidar. In contrast, signals from the near edge of the second cloud layer are severely affected by the photons emerging from the first layer in the case of a space-borne lidar.

We evaluated the Eloranta model (EM) (Eloranta, 1998) in extreme conditions and showed its good performance in the cases of ground-based and space-borne (CALIOP) lidars. When the extinction coefficient is about 1.0 km^{-1} or lower, and the EFOV and the RFOV are quite narrow, five orders of scattering are sufficient to obtain satisfying accuracy of simulations. At the same time, we revealed the shortcoming that affects practical applications of the EM. Namely, values of the key parameters, i.e. of the ratios $\mathcal{P}_n(\pi, h)/\mathcal{P}_1(\pi, h)$ of phase functions in the backscatter direction for the nth-order-scattered photon and a singly scattered photon depend not only on the particles phase function, but also on the distance from a lidar to the cloud and the receiver field of view. Values of the ratios $\mathcal{P}_n(\pi, h)/\mathcal{P}_1(\pi, h)$ vary within a quite large range. Therefore, the multiple scattering contribution to lidar signals can be largely overestimated or underestimated if erroneous values of the ratios are assigned to the EM. That problem can be circumvented by using Monte Carlo simulations or the empirical model (Shcherbakov et al., 2022) to calibrate the ratios $\mathcal{P}_n(\pi, h)/\mathcal{P}_1(\pi, h)$.

Appendix A: Input parameters of the Eloranta model in homogeneous-cloud conditions

A.1 Eloranta model

We have chosen to evaluate the Eloranta model (EM) (Eloranta, 1998) due to its following attractive features. The input parameters have clear physical meaning. The contribution of each nth-order of scattering can be computed separately. The corresponding code can be developed without much difficulty because multiple integrals are the core of the EM. The good performance of the Eloranta model (EM) (Eloranta, 1998) in homogeneous-cloud conditions has already been reported in the literature (see e.g. Eloranta, 1998; Donovan and Van Lammeren, 2001). In our opinion, our results above demonstrate the reliability of the EM in extreme conditions, i.e. when the extinction coefficient has undergone a stepwise jump. The objective of this appendix is to reveal some significant features of the EM's input parameters that are related to the particles phase function.

We developed two versions of codes based on the EM. The first version corresponds to Eq. (8) of (Eloranta, 1998). In order to avoid ambiguity, we rewrite that equation in a way that all functions, including $\varepsilon(x)$, $\gamma(x)$, and $\Theta_s(x)$, are assigned in the coordinate system where the lidar is at $h = 0$ and h is the distance from the lidar

$$R_{nto1}(h) = \frac{\mathcal{P}_n(\pi,h)}{\mathcal{P}_1(\pi,h)}\left[1 - \exp\left(-\frac{\rho_t^2}{\rho_l^2}\right)\right]^{-1} \cdot \left\{\int_{-d}^{d} \gamma(h-|x_1|) \cdot \varepsilon(h-|x_1|) \int_{x_1}^{d} \gamma(h-|x_2|) \cdot \varepsilon(h-|x_2|) \cdots \int_{x_{n-2}}^{d} \gamma(h-|x_{n-1}|) \cdot \right.$$

$$\left. \varepsilon(h-|x_{n-1}|) \cdot \left[1.0 - \exp\left(-\frac{\rho_t^2 h^2}{x_1^2\Theta_s^2(h-|x_1|) + x_2^2\Theta_s^2(h-|x_2|) + \cdots + x_{n-1}^2\Theta_s^2(h-|x_{n-1}|) + \rho_l^2 h^2}\right)\right] dx_{n-1} \cdots dx_2 \, dx_1\right\}. \tag{A1}$$

$n \geq 2$, $\varepsilon(h) = \varepsilon_p(h) + \varepsilon_m(h)$, $\varepsilon_p(h)$ and $\varepsilon_m(h)$ are the particles and the molecular extinction coefficients, respectively. The function $\gamma(h)$ is the fraction of the energy in the forward peak of the phase function, h_b is the distance from the lidar to the cloud near edge, $d = h - h_b$. If calculations are performed only within a cloud, d is just the cloud penetration depth. As usual, the notation $|x_i|$ means the absolute value of x_i. ρ_t is the half-angle of the receiver field of view, ρ_l is the half-angle of the emitter divergence. Θ_s is the $1/e$ diffraction peak angular half width (Whiteman et al., 2001), in other words, Θ_s is the parameter that characterises a Gaussian approximation for the forward scattered peak. Θ_s can be estimated using the relationship (Eloranta, 1998; Hogan, 2006)

$$\Theta_s = \lambda/(\pi r_G), \tag{A2}$$

where r_G is the equivalent-area radius of the particles size distribution, λ is the wavelength.

Other input parameters of the EM are the ratios $\mathcal{P}_n(\pi,h)/\mathcal{P}_1(\pi,h)$ of phase functions in the backscatter direction for the nth-order-scattered photon and a singly scattered photon (Whiteman et al., 2001). It is assumed that the backscattered phase function $\mathcal{P}_n(\pi,h)$ for n^{th}-order scattering is independent of angle near $180°$ with a value, which is a weighted average near the backscatter direction (Eloranta, 1998). The following is underlined in the work (Eloranta, 1998): "For observations it will be necessary to use assumed values. For typical phase functions, $\mathcal{P}_n(\pi,h)/\mathcal{P}_1(\pi,h)$ is between 0.5 and 1."

The second version of the EM code correspond to Eq. (11) of (Eloranta, 1998), where the constant value $\gamma(x) = 1/2$ was

635 assumed using a reference to diffraction theory. We reproduce the equation for n^{th}-order of scattering with the reformulation outlined in (Eloranta, 2000; Whiteman et al., 2001) (see Eq. (13) in Eloranta, 2000) and using our notations

$$R_{nto1}(h) = \frac{\mathcal{P}_n(\pi,h)}{\mathcal{P}_1(\pi,h)} \left[1 - \exp\left(-\frac{\rho_t^2}{\rho_l^2}\right)\right]^{-1} \cdot \left\{\frac{\tau^{n-1}(h_b,h)}{(n-1)!} - \int_{h_b}^{h} \varepsilon(x_1) \int_{x_1}^{h} \varepsilon(x_2) \cdots \int_{x_{n-2}}^{h} \varepsilon(x_{n-1}) \cdot \right.$$

$$\left. \exp\left(-\frac{\rho_t^2 h^2}{(h-x_1)^2 \Theta_s^2(x_1) + (h-x_2)^2 \Theta_s^2(x_2) + \cdots + (h-x_{n-1})^2 \Theta_s^2(x_{n-1}) + \rho_l^2 h^2}\right) dx_{n-1} \cdots dx_2\, dx_1 \right\} \tag{A3}$$

where $\tau(h_b, h) = \int_{h_b}^{h} \varepsilon(x) dx$ and other notations have the same meaning as in Eq. (A1).

640 We used Eqs. (A1) and (A3) only in cases when $h \geq h_b$; we have verified that the first version of the EM code, i.e. Eq. (A1), gives the same results as Eq. (A3) if the constant value $\gamma(x) = 1/2$ is assigned in Eq. (A1). We tested our codes of the EM against the data available in the literature. All test were performed with $\gamma(x) = 1/2$. We obtained perfect agreement with Figs. 6-8 of the work (Eloranta, 1998) using $\mathcal{P}_n(\pi, h)/\mathcal{P}_1(\pi, h) = 0.75, n = 2, 3, 4$ and with Fig. 15(b) of the work (Donovan and Van Lammeren, 2001) using $\mathcal{P}_n(\pi, h)/\mathcal{P}_1(\pi, h) = 1.0, n = 2, 3, 4$.

645 **A.2 Input parameters**

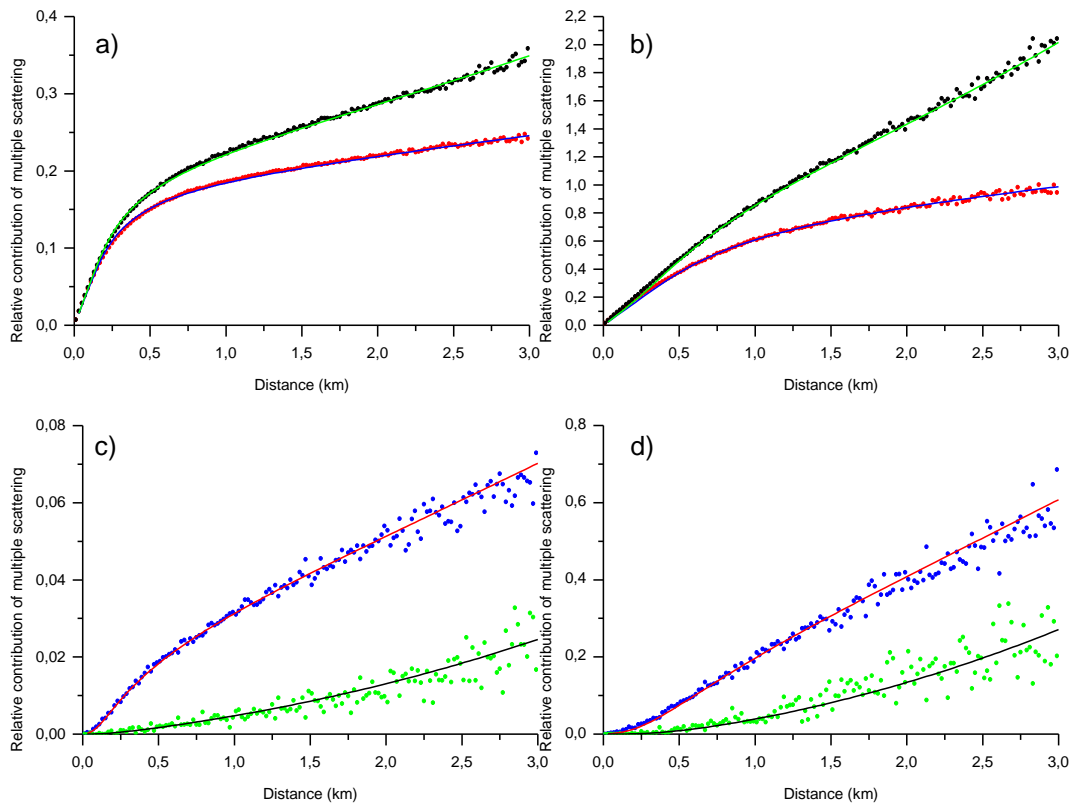
The results reported in Fig. A1 were obtained for the same configuration that was described above (see Section 3.1). That is, a ground-based lidar is at the altitude $H = 0$. km; the distance to the clouds base is 8 km. The full RFOV is 1.0 mrad; the full EFOV is 0.14 mrad. The emitter wavelength λ is 0.532 µm. The single-layer homogeneous cloud is within the altitude range $H \in [8., 11.]$ km, has the optical thickness $\tau_p = 3.0$, i.e. cloud particles have the extinction coefficient $\varepsilon_p(h) = 1.0$ km^{-1}.

650

Figure A1. Monte Carlo simulations of multiple scattering R_{MSto1} (black points), double scattering R_{2to1} (red points), the third $R_{3to1}(d)$ (blue points) and the forth $R_{4to1}(d)$ (green points) orders, respectively, relative contributions to lidar signals; (a, c) water cloud, (b, d) jet-stream cirrus. Eloranta-model simulations are green (MS), blue (double scattering), red (third order), and black (forth order) curves.

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The results of the Monte Carlo modeling (points) and the EM's simulations (lines) are shown in Fig. A1 only for the in-cloud range $d \in [0.,3.]$ km, i.e. the altitude interval $H \in [8., 11.]$ km. Figures A1a and A1c correspond to the water cloud, Figs. A1b and A1d to cirrus cloud. The microphysical and optical parameters of cloud particles are done in Section 2.2 above. The results of each case are divided into two panels; Figs. A1a and A1c show the relative contribution of multiple $R_{MSto1}(d)$ (black points

660 and green line) and double $R_{2to1}(d)$ (red points and blue line) scattering; Figs. A1b and A1d show the relative contribution of the third $R_{3to1}(d)$ (blue points and red line) and the forth $R_{4to1}(d)$ (green points and black line) orders. In other words, the lower panels are complementary to the corresponding upper panels. (Note that each panel in Fig. A1 has its own scale of the y-axis.)

The good agreement between the MC and EM data is evident. That agreement was obtained by adjusting the EM parameters

665   by the following way. The distance h_b to the cloud near edge, the extinction coefficient $\varepsilon_p(d)$, the half-angle ρ_t of the receiver field of view, and the half-angle ρ_l of the emitter divergence were assigned according the configuration used for the MC simulations. First, we found the values of Θ_s and $\mathcal{P}_2(\pi)/\mathcal{P}_1(\pi)$ by fitting the MC data on $R_{2to1}(d)$ with the Eloranta model using the ordinary least squares approach. Then we found the values of $\mathcal{P}_3(\pi)/\mathcal{P}_1(\pi)$ and $\mathcal{P}_4(\pi)/\mathcal{P}_1(\pi)$ by fitting the MC data on $R_{3to1}(d)$ and $R_{4to1}(d)$, respectively. We have limited our EM simulations by five orders of scattering. Consequently,

670   the ratio $\mathcal{P}_5(\pi)/\mathcal{P}_1(\pi)$ was computed to fit the remained part of the total multiple scattering.

Table A1. Fitting values of the EM parameters.

	Ground based lidar		Space-borne lidar	
	Water cloud	JS cirrus	Water cloud	JS cirrus
Θ_s (rad)	0.01882	0.0064	0.01882	0.0064
Θ_s (degree)	1.078	0.3667	1.078	0.3667
$\mathcal{P}_2(\pi)/\mathcal{P}_1(\pi)$	0.502	0.7721	0.4993	0.8211
$\mathcal{P}_3(\pi)/\mathcal{P}_1(\pi)$	0.395	0.66	0.5	0.99
$\mathcal{P}_4(\pi)/\mathcal{P}_1(\pi)$	0.33	0.51	0.4	0.99
$\mathcal{P}_5(\pi)/\mathcal{P}_1(\pi)$	0.26	0.553	0.35	0.99

The obtained values of parameters are shown in Table A1. The value of Θ_s is in good agreement with Eq. (A2) for the water cloud, it is about 7% higher for the jet-stream cirrus. The important result is the fact that the values of the ratios

675   $\mathcal{P}_n(\pi)/\mathcal{P}_1(\pi), n = 2, \dots, 5$ are quite small, especially for the water cloud, and they decrease with the order of scattering increasing. If the recommendation of the work (Eloranta, 1998), i.e. "for typical phase functions, $\mathcal{P}_n(\pi, h)/\mathcal{P}_1(\pi, h)$ is between 0.5 and 1", is applied, the effect of the multiple scattering will be largely overestimated in the case of the water cloud. In our opinion, the cause of small values of the ratios $\mathcal{P}_n(\pi)/\mathcal{P}_1(\pi)$ and of the declining $R_{MSto1}(d)$ in the free atmosphere range is common, i.e. photons, scattered in forward and backward directions, escape the sampling volume.

680   We performed the same kind of work for the case of space-borne lidar and the configuration described in Section 4.1.1. In other words, we provide the values of parameters when the same cloud was probed by the ground-based and the space-borne lidars. The obtained values of parameters are shown in Table A1 as well. It is seen that the values of the ratios $\mathcal{P}_n(\pi)/\mathcal{P}_1(\pi)$ depend not only on the phase function of particles, but also on the lidar configuration, especially on the distance, the RFOV, and the EFOV.

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Appendix B: An example of simulation-uncertainty analysis

It is well known that Monte Carlo modeling provides an estimate of the parameter of interest, i.e. the value that is affected by an error (an estimate minus a true value of the parameter). That error is a random variable whose mean is zero and whose width is characterized by the corresponding variance. The error is due to the statistical nature of Monte Carlo computations (see e.g.
690 Kalos and Whitlock, 2008). In other words, a Monte Carlo estimate, like a measurement, has imperfections that give rise to a random error. Such similarity provides grounds to perform simulation-uncertainty analysis using the same approach as in measurement-uncertainty analysis.

Table B1 shows the relative errors (RE) computed according to the Document of the Joint Committee for Guides in Metrology (JCGM 100:2008) for our simulation data in the case of the space-borne lidar (see Section 4.1.1 for details and the notations).
695 The estimate of variance was obtained using individual simulation replications (see e.g. Bicher et al., 2022). The altitudes H 12.01 and 6.01 km correspond to the cloud-free molecular atmosphere; $H =$10.99 and 8.01 km correspond to the near edge and the far edge, respectively, of the cloud. The altitudes 10.99, 8.01 and 6.01 km correspond to the distances $d = 0.01$, 2.99 and 5.99 km, respectively, in Fig.7. The MS contribution to lidar signals as well as the values of R_{MSto1} are close to zero at the altitudes 12.01 and 10.99. Therefore, the corresponding relative errors are not shown in Table B1.

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Table B1. Relative error in per cent (%) of MC simulations.

	12.01 km	10.99 km	8.01 km	6.01 km
Water cloud S_1	0.37	0.03	1.33	0.77
Water cloud S_{MS}	0.37	0.03	6.78	8.78
Water cloud R_{MSto1}			8.68	15.84
Jet-stream cirrus S_1	0.37	0.05	2.19	0.80
Jet-stream cirrus S_{MS}	0.37	0.05	10.25	14.44
Jet-stream cirrus R_{MSto1}			11.23	31.24

The relative errors RE in Table B1 can be discussed on the base of the following relationship (Rubino and Tuffin, 2009)

$$RE \sim \frac{1}{\sqrt{N} \cdot \sqrt{\chi}}, \tag{B1}$$

705 where N is the sample size, i.e. the number of photons emitted by the lidar ($2 \cdot 10^{11}$ and $4 \cdot 10^{11}$ for the water the cirrus clouds, respectively). χ is the probability of an event, i.e. the probability that an emitted photon interacts with cloud particles or the molecular atmosphere within the strobe at the altitude of interest and is scattered towards the lidar within the receiver FOV. It is evident that MC modeling of lidar signals deals with rare events, i.e. the probability χ is extremely low. χ depends on particles characteristics, for example it is inversely proportional to the lidar ratio. It is proportional to the extinction coefficient.
710 Therefore, the RE is much better at the altitude 10.99 km compared to 12.01 km. The probability χ is proportional to the

strobe width. For example, it follows from Eq. B1 that the relative error would be two times lower is the strobe was four times wider, i.e. the vertical resolution was four times worse.

To conclude this section, we underline that the quality of MC modelling can be judged by the dispersion of the data points in a figure as well as by values of relative errors. That is why we did not perform any smoothing of our MC data leaving the reader to see the data quality in our figures.

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Data availability. The data of simulations are available from the corresponding author upon request.

Author contributions. VS, FS, GM, and CC contributed to developing the McRALI code, numerical simulations, and data

720 treatment. VS wrote the manuscript with help from FS. FS and GM acquired funding.

Competing interests. The contact author has declared that neither they nor their co-authors have any competing interests.

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730

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