Full scale experiments to examine the role of deadwood on rockfall dynamics in forests

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Abstract. Forests are rockfall-protective ecological infrastructures, as a significant amount of kinetic energy is absorbed during consecutive rock-tree impacts. Although many recent works have considered rock impacts with standing trees, the effect of lying deadwood in forests has not yet been considered thoroughly, either experimentally or numerically. Here, we present a complete examination of induced rockfall experiments with sensor-equipped, 45 kg, artificial rocks on a forested area in three different management stages. The trilogy is conducted in a spruce forest stand (i) in its original state of forest, (ii) after a logging operation with fresh, lying deadwood and (iii) after the removal of the deadwood. The tests allow us to directly quantify the effect of fresh deadwood on overall rockfall risk for the same forest (slope, species) under three different conditions. The study yields quantitative results on the barrier efficiency of the deadwood logs as only 3.6 % of the rocks surpass the deadwood section. The mean runout distance is reduced by 42 %. Conversely, the runout distance increases by 17 % when the cleared stand is compared to the original forest. These results quantitatively confirm the benefits of nature-based mitigation measures integrated into forestry practice, whose detailed effect has to be scrutinized for higher rockfall energies. Based on the experimental results, we extended a modern rockfall code by three-dimensional deadwood logs, to incorporate such complex, but realistic forest boundary conditions.

1 Introduction

Rockfall is a common natural hazard in mountain regions. Up to certain rockfall magnitudes, protection forests are effective ecological infrastructures to reduce rockfall intensities and thus the damage on vulnerable facilities as falling rocks are decelerated by consecutive tree impacts. This has been shown by real scale experiments at the slope scale in a mixed Abies-Picea-Fagus forest (Dorren and Berger, 2005) as well as on single trees of different species including *Picea abies*, (Lundström et al., 2009) and *Ailanthus altissima*, (Wunder et al., 2018). Implementation of these findings into three dimensional rockfall models, e.g. Rammer et al. (2010); Dorren (2012); Toe et al. (2017); Lu et al. (2020), facilitated additional investigations to

quantify the protective capacity of mountain forests using numerical tools at the forest stand (Stoffel et al., 2006; Woltjer et al., 2008; Moos et al., 2017) and regional scales (Dupire et al., 2016; Lanfranconi et al., 2020).

Experimental tests to investigate the role of deadwood for rockfall mitigation have also been performed at the laboratory (Ammann, 2006; Olmedo et al., 2015) and slope (Bourrier et al., 2012) scales. The laboratory studies provided the first quan-
titative insights into the protective effects of deadwood but do not accurately represent natural deadwood configurations after disturbances since the investigators used clumped *Picea abies* and *Fagus sylvatica* specimens with relatively small mean diameters of 26 cm and 6 cm (Ammann, 2006; Olmedo et al., 2015). The field studies of Bourrier et al. (2012) used larger 63 cm diameter logs fixed to tree stumps using steel cables. How deadwood is naturally fixed (jammed) between trees and the ground is essential to understand its protective capacity and therefore man-made fixations may also not represent natural conditions
in mountain forests. As a consequence, present approaches to include deadwood into a three dimensional rockfall model are based on slope or roughness adaption methods combined with higher, and empirically determined, rock-ground restitution coefficients (Fuhr et al., 2015; Costa et al., 2021).

Neither the different experimental nor the modeling approaches take piled stems into account, which are often the result of uprooted trees during windthrow events. Beside windthrows (Feser et al., 2015), also bark beetle outbreaks (Jönsson et al.,
2009) and forest fires (Mozny et al., 2021; Jain et al., 2020) are likely to increase in frequency or amplitude due to climate change and land-use legacies. Allowing natural processes without salvage logging after windthrow and without sanitary felling after bark beetle are increasingly promoted as adequate management option (Kulakowski et al., 2017; Sommerfeld et al., 2021). In rockfall protection forests, it is decisive to know more on the short- and long-term effects of piled stems on rockfalls after natural disturbances or management interventions.

In this paper, we present the results of three induced rockfall experiments within the same mountain forest but in three different management states. First, we performed rockfall experiments in the original, undisturbed forest. In the next series of tests, the effect of lying, partly piled, fresh deadwood in the upper third of the slope was tested. The "deadwood" was created after a forest management intervention and was therefore in a fresh condition with maximal physical resistance. In the final test series, the deadwood was cleared (the final forest was therefore sparser than the original forest). All three tests were performed
in the same spruce stand to explore the protection effect of lying deadwood quantitatively. A three-dimensional rockfall model was extended with truncated cones as deadwood logs and calibrated based on the experimental results to facilitate investigations of deadwood mitigation measures at other rockfall-endangered sites.

2 Material and methods

2.1 Study site: Surava

The study site (46.65720° N, 9.60497° E, 1120 m a.s.l.) covers 0.54 ha of north-west exposed, roughly 35° steep mountain forest in the community Surava within the municipal area of Albula/Alvra, Switzerland. In a complete forest inventory the diameters at breast height (DBH), tree species and GNSS-positions of all trees with DBH $\geq$ 8 cm were recorded, resulting in a total of 462 trees, a stand density of 855 trees ha^{-1} and a mean DBH of 23.9 $\pm$ 11.7 cm, see Figure 1.a). The principal

tree species are Norway spruce (78.8 %, *Picea abies* (L.) Karst.), European larch (9.5 %, *Larix decidua* Mill.), mountain pine
(6.7%, *Pinus mugo* subsp. uncinata (DC.) Domin.) and silver fir (4.1 %, *Abies alba* Mill.). Further single rowans (*Sorbus aucuparia* L.), beeches (*Fagus sylvatica* L.) and whitebeams (*Sorbus aria* (L.) Crantz) were registered.

2.2 Experimental set-up

Rockfall experiments were conducted during three different states of forest: in the original forest (**ORG**), after a logging operation with lying, partly piled deadwood (**DW**) and subsequently with this area cleared (**CLR**). The regeneration cut was located in the top third of the former even-aged spruce stand. Its area covered about 700 m^2 and comprised 53 trees, of which 26 trunks were left lying for the CLR-experiments (Fig. 1.a). We used perfectly symmetrical reinforced *EOTA* concrete rocks (ETAG 027, 2013) with a mass of 45 kg and a diameter of 0.29 m (Fig. 3.d). The diameter of a *EOTA* rock is defined as the distance between two opposing flat surfaces. This mass allowed still a manual rock handling, even if rocks stuck between deadwood logs. In a borehole through its center of mass, in situ StoneNode v1.3 sensors were mounted to record rotational velocities (ω) in all three axis up to 69.8 rad·s^{-1} (= 4000°·s^{-1}) and accelerations up to 3922.66 m·s^{-2} (= 400 g) with a sampling rate of 1 kHz (Niklaus et al., 2017; Caviezel et al., 2018).

The rocks were repeatedly released manually from the same starting position at 1118.5 m a.s.l.: 42 runs in the **ORG**, 28 runs in the **DW**, and 41 runs in the **CLR** state of the forest, of which at least 73 % per state include the in situ sensor streams. The deposition points of the rocks were measured with a high-precision Trimble GeoXH differential handheld GNSS reduced to a mean horizontal accuracy of 1.6 m in this steep north-west exposed forest. Thereafter the rocks were winched back from its deposition point to the forest road and from there transported by four wheel motorcycle back to the release-point.

To compare the deposition pattern between the three states of the forest quantitatively, the geographic mean centre (GMC), the third standard deviation ellipse (SDE) and its radius of the long (SDE$_{la}$) and short axis (SDE$_{sa}$) were calculated based on the python code provided by Schelp (2018) . The mean run out distance (MROD) is the euclidean, slope parallel distance between release point and GMC.

2.3 Sensor data processing

In order to detect frontal impacts (FI) on opposing objects such as standing trees, overturned root plates or larger rocks, we applied gyroscopic data-analysis, rather than evaluate the acceleration data, since the latter vary strongly depending on the incoming translation velocity and especially the material being hit. Regardless of the material, after an FI, a sharp reduction in the resulting rotational velocity will occur. We generated smoothed gyroscopic data streams by applying five different moving window sizes (0.001 s, 0.021 s, 0.061 s, 0.101 s, and 0.151 s, Fig. 3.e) to reliably detect such abrupt changes in the resultant gyroscopic data stream. On each of these streams, we executed the *Matlab* function *ischange* (Killick et al., 2012) with its *linear* method. The corresponding, empirically determined segment slope thresholds ($\leq -100, \leq -29, \leq -21, \leq -9.75$, and ≤ -6.5) define the minimal decrease of rotational velocity within each moving window to flag a FI (Fig. 3.f). For robustness reasons, at least three out of five thresholds must be reached for a confirmed FI.
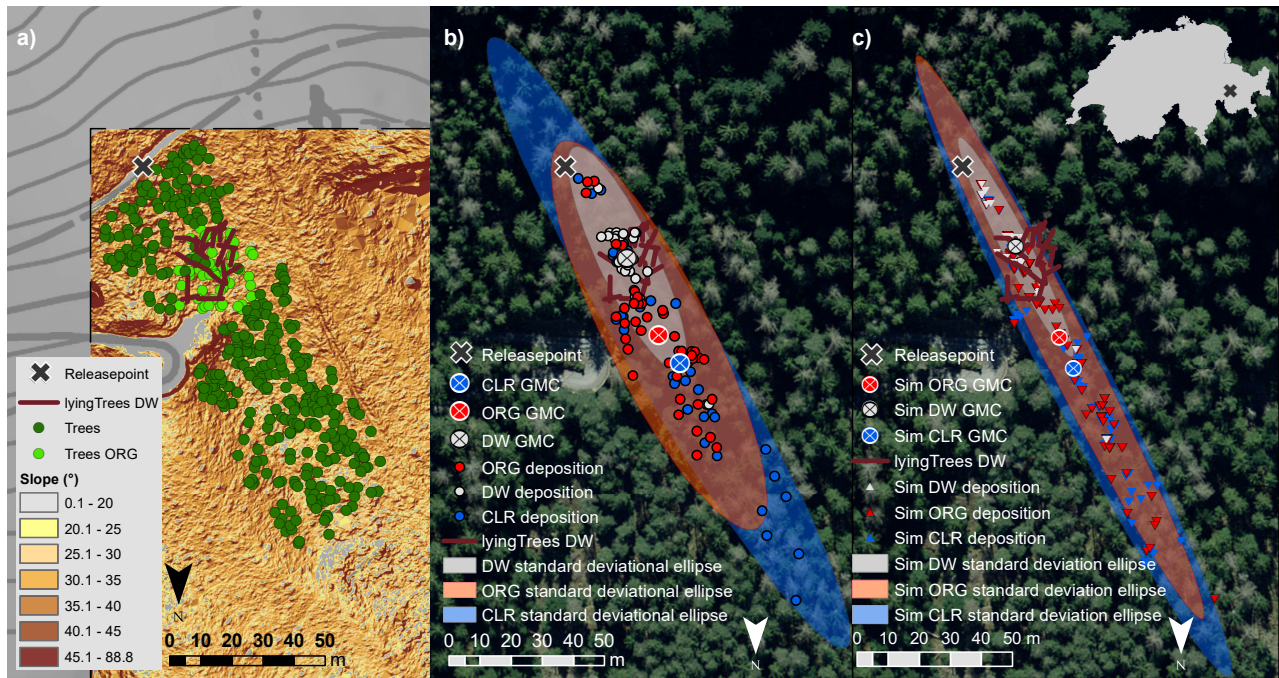
Figure 1. Overview of the experimental test site Surava: a) Slope map with the standing trees during the whole trilogy (dark green circles), during ORG state (light green circles) and lying deadwood during DW (brown lines). b) Deposition points of all 111 runs of the 45 kg EOTA$_{111}$ rocks including all three states of the forest: ORG in red, fresh DW in grey and CLR in blue. The corresponding geographic mean centers (GMC) are shown with crossed symbols in the corresponding color. Additionally the third standard deviation ellipse (SDE) of each data set, are depicted as transparent ellipses. c) deposition point of the total 300 simulated trajectories under consideration of the three states of the forest. The GMC and SDE are in the corresponding colors of the experimental results. Source of topographical map (a) and orthophoto (b,c): Federal Office of Topography

2.4 Rockfall simulations

The experimental rockfall trilogy was emulated with a rigid body rockfall code that includes compactable soils (Lu et al., 2019) and standing single trees (Lu et al., 2020). Based on the measured DBH, the in RAMMS::ROCKFALL used tree height was estimated based on $H = DBH^{\frac{1}{1.25}}$ (e.g. Dorren (2017)). To represent the conditions of the **DW** state of the forest, we introduce
90   three-dimensional, rigid, truncated cones, representing lying deadwood. During fieldwork, all 26 trunk GNSS positions were recorded, but not the exact diameters nor the height above ground of every log end, which are required as input parameters for the generation of the individual deadwood cone in RAMMS::ROCKFALL. As a realistic but simplified approach, we assumed a uniform maximal diameter of 40 cm for all deadwood-logs. If logs were lying on top of each other, we considered the in the GNSS-file first mentioned as the lower log with ground contact, and the latter piling up.
95   Current surface models from the Swiss Federal Office of Topography swisstopo are available with resolutions as fine as 0.5 m grid size. The need to account for mesoscale roughness effects as well as customized ground point detection algorithms,
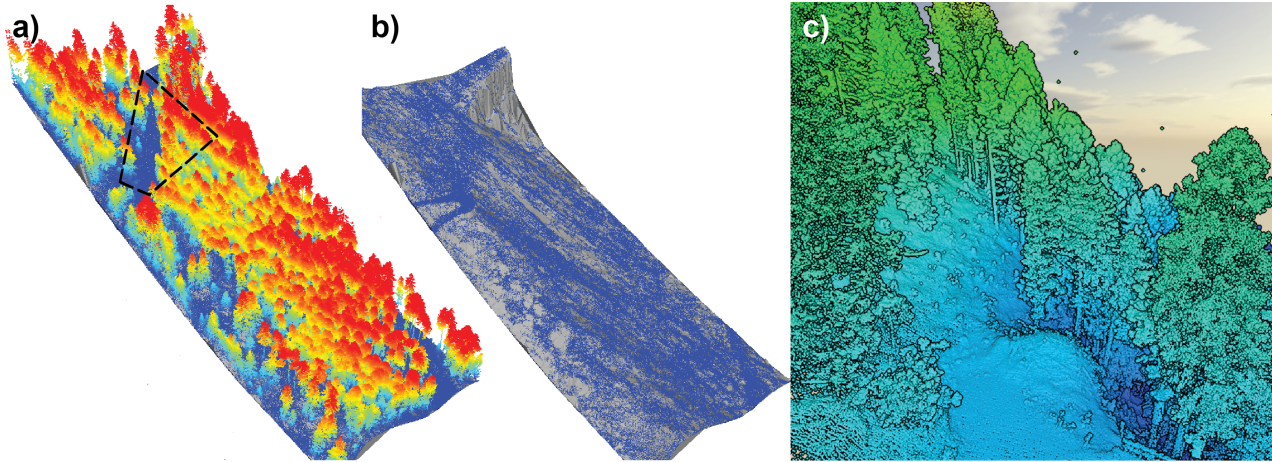
Figure 2. a) The acquired LiDAR point cloud colored according to the height above ground (blue = 0 m, red $\geq$ 23 m). b) LAStool post-processed ground points used to generate a high-resolution digital surface model for the rockfall simulations. c) Zoomed-in section of the cleared area as indicated in a). The mesoscale surface roughness is clearly discernible in the ground points in the cleared area as well below the remaining tree canopy.

nonetheless demanded a site-specific airborne LiDAR mission. The LiDAR point cloud has a density $\geq$ 500 points$\cdot$m^{-2} and was scanned by an Trimble AC60 sensor, after the CLR-experiments (Fig. 2). The generated digital surface models with a resolution of 0.05 m, processed in the LAStool-framework with the $-extrafine$ option, specialized to detect ground points in steep mountainous regions (Isenburg, 2021), was used for the simulation of all states of the forest.

The soil mechanical strength M_E and the scar drag coefficient C_d are the soil parameters to calibrate (Lu et al., 2019; Caviezel et al., 2019b). We performed simulations sweeps within the relatively wide range of $0.8 \leq M_E \leq 2.6$ kN$\cdot$m^{-2} and $1.7 \leq C_d \leq 3.0$ where the parameters of soft soils should be located. Runs with 300 orientations were performed to narrow down the parameter ranges for the in-depth calibration. Subsequently a model run with 3000 initial rock orientations per forest state and M_E and C_d pairs within the ranges of $1.6 \leq M_E \leq 2.1$ kN$\cdot$m^{-2} and $2.6 \leq C_d \leq 3.1$ and with a step size of 0.1 was performed. The calibration is based on the comparison of simulated versus experimental deposition patterns, more precisely its standard deviational (or directional distribution) ellipse. The fit per state was calculated and summed up in the overall fit (OF_{3000}) over all states:

$$S_{\text{FIT}} = |\text{MROD} - \text{MROD}_{sim}| + |\text{SDE}_{\text{la}} - \text{SDE}_{\text{lasim}}| + |\text{SDE}_{\text{sa}} - \text{SDE}_{\text{sasim}}| \tag{1}$$

where the scenario S is either **ORG**, **DW**, or **CLR**. The sum of all the scenario fits amount to the overall fit

$$OF_{3000} = \text{ORG}_{\text{FIT}} + \text{DW}_{\text{FIT}} + \text{CLR}_{\text{FIT}} \tag{2}$$

This metric allows to quantify the differences between experimental scenarios as well as the congruence between experiment and simulation. To reduce scaling effects due to the massively higher number of simulations (3000) relative to the experiments,

additionally packages of 100 trajectories were randomly drawn and compared to the results of the experiments, consequently
labeled as OF_{100}.

3 Results

3.1 Rockfall experiments

None of the 111 released $EOTA_{111}$ rocks were capable of breaking a tree or a deadwood log. The effect of lying deadwood had an important influence on the observed rockfall dynamics for the investigated weight class summarized in Tab. 1 and visualized in Fig. 1.b: The mean slope parallel run out distance (MROD) is reduced by 42.1% when comparing the **DW** to the **ORG** state of the forest. The effect of the removed standing trees between **ORG** and **CLR** is visible in the prolongation of the MROD by 17.7%. The DW_{MROD} reduction is accompanied by an increase of the mean shadow angle DW_α by 1.3° and 1.4° compared to ORG_α and CLR_α. The use of standard deviation analysis implies an compliant data set. The presented data confirms this assumption, except from the longitudinal deposition pattern for the **DW** state, based on the normal-distribution test ($scipy.stats.normaltest$, $\alpha = 0.05$) for the x- an y- deposition coordinates, after a conducted principal components rotation ($sklearn.decomposition.PCA$).

The similar grouping among the forest configurations is also for the in situ measured data visible: The two-sample t-test produced significant ($\alpha = 0.05$) differences between the mean run time, the maximal accelerations of the **DW** state and the corresponding variables of the **ORG** and **CLR** states. Within **ORG** and **CLR**, the differences are not significant within the chosen level.

The number of detected FI on opposing objects was between 0.90 (**ORG**) and 0.43 (**DW**) per run. Based on slope parallel distance between starting and deposition point and the run time from the sensor stream, the mean-velocity for each run is calculated. The longer MROD influences also the mean run time, but not linearly: rocks in the **DW** state were moving on average for 14 s, which results in a mean velocity of 2.9 m s^{-1}. The states **ORG** and **CLR** feature run times of 19 s and 23 s, respectively. In conjunction with their longer run out distances, **ORG** and **CLR** surpass the **DW** state by a 28% higher velocity.

3.2 Rockfall Simulations

The parameter pair $M_E = 2.0$ and $C_d = 2.9$ yield the best overall fit (OF) over all 3000 simulation ($OF_{3000} = 83.0$ m) and of any randomly sampled package of 100 trajectories ($OF_{100} = 58.7$ m). The parameter robustness is highlighted by the 10th best fit: $OF_{3000}^{R10} = 86.5$ m only having a 4.3 % higher deviation. The following analysis (Tab. 1 and Fig. 4) focuses on the trajectory-package with the best OF_{100}. The experimentally observed MROD reduction of the deadwood was recognizable in the simulations: The **DW**-simulations had a slightly (5.9 m, 14%) shorter MROD as the experiments, but a similar length of the SDE_{la}. While the MROD and its SDE_{la} of the **CLR** state-simulations were both within the experimental GNSS-accuracy, the ORG simulations show a good fit in the MROD, but a larger longitudinal spread of SDE_{la} as recorded during the experiments.
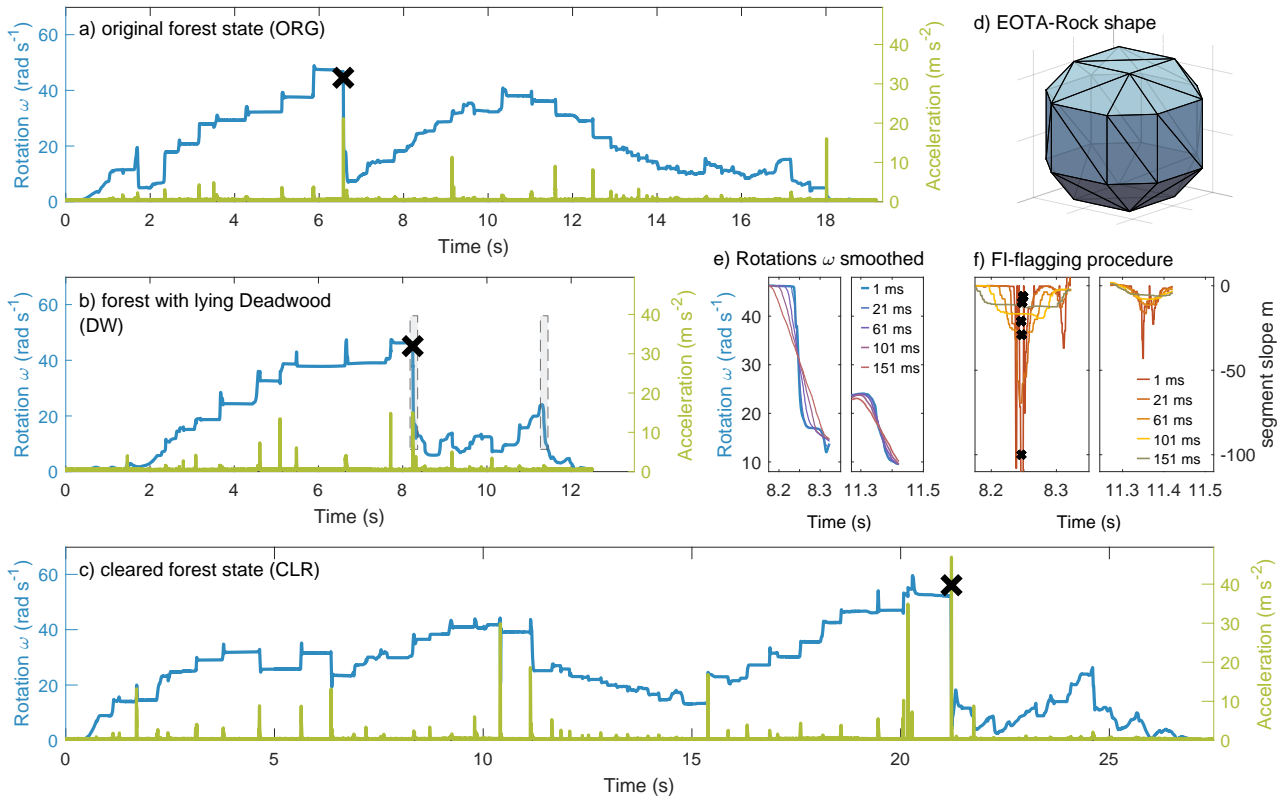
Figure 3. Example of three typical StoneNode data streams a)-c) measured within the 45 kg EOTA_{111} rocks (d): in blue the resulting rotational velocities, in green the resulting impact accelerations of a) an ORG-run, b) a DW-run and c) a run within the CLR-stand. The confirmed frontal impacts (FI) therein are marked as large black crosses, their flagging procedure exemplified in e) and f) for two hits outlined in gray in c). (e) Smoothed rotations ω with different moving window sizes and (f) segment slopes m of linear segments in smoothed ω. If falling below the moving-window specific threshold, the impact is flagged as possible FI (small black crosses), prevailing as confirmed FI if at least three flags are produced for the same impact.

The overall good fit of the simulated MROD consequently leads to a good agreement of the simulated mean shadow angles. The simulated mean run time for the shorter runs of the **DW** state are consistent with the experiments (-4.4%). The run times for the **ORG** (+45.8%) and **CLR** (+37.6%) are by contrast considerably overestimated and the velocities therefore underestimated.

Although the trend of the simulated average maximum accelerations between the states of the forest is correct, the simulations globally underestimate the experimental values by roughly 40%. The simulated maximal rotational velocities per run are between 31.9 % - 36.4 % lower as the results of the experiments. A less pronounced underestimation, 15.6% for **DW**, 30% for **ORG**, was detected for the mean rotational velocities. Within the simulated rotational data stream, no FI could have been detected with the same thresholds.

Table 1. Resulting statistics of the experiments (left) and Simulations (right) for the original state of the forest (**ORG**), the state with lying, fresh deadwood (**DW**) and the deadwood cleared area (**CLR**)).

		Experiments			Simulations		
		ORG	DW	CLR	ORG	DW	CLR
N° Runs/with Sensor data		42/42	28/21	41/34	100/100	100/100	100/100
mean run out distance± SD	(m)	74.3±27.2	43.1±15.4	87.5±42.7	75.4±39.8	37.2±15.7	88.4±43.4
mean shadow angle± SD	(°)	34.4±1.2	35.6±0.8	34.2±1.3	34.9±1.3	36.2±0.8	34.6±1.7
mean run time ± SD	(s)	19.2±6.4	13.7±5.2	21.2±11.4	27.7±16.2	13.1±6.0	31.5±16.6
mean max. acc. per run ± SD	(g)	265.8±98.1	217.0±83.0	265.3±85.4	152.6±49.4	138.5±47.2	164.3±45.7
mean max. ω per run ± SD	$(rad \cdot s^{-1})$	48.3±6.5	45.6±6.3	45.7±10.5	30.7±3.6	30.7±3.7	31.1±3.1
mean average ω per run ± SD	$(rad \cdot s^{-1})$	20.8±3.3	17.3±2.8	18.7±4.5	14.2±2.0	14.6±2.2	14.4±2.0
mean N° FI per run ± SD	(-)	0.88±0.89	0.43±0.51	0.57±0.65	-	-	-
mean N° FI per run time ± SD	(s^{-1})	0.049±0.049	0.032±0.041	0.031±0.043	-	-	-
mean velocity ± SD	(ms^{-1})	3.7±1.2	2.9±0.6	3.7±0.8	3.0±0.4	3.1±0.5	3.0±0.4
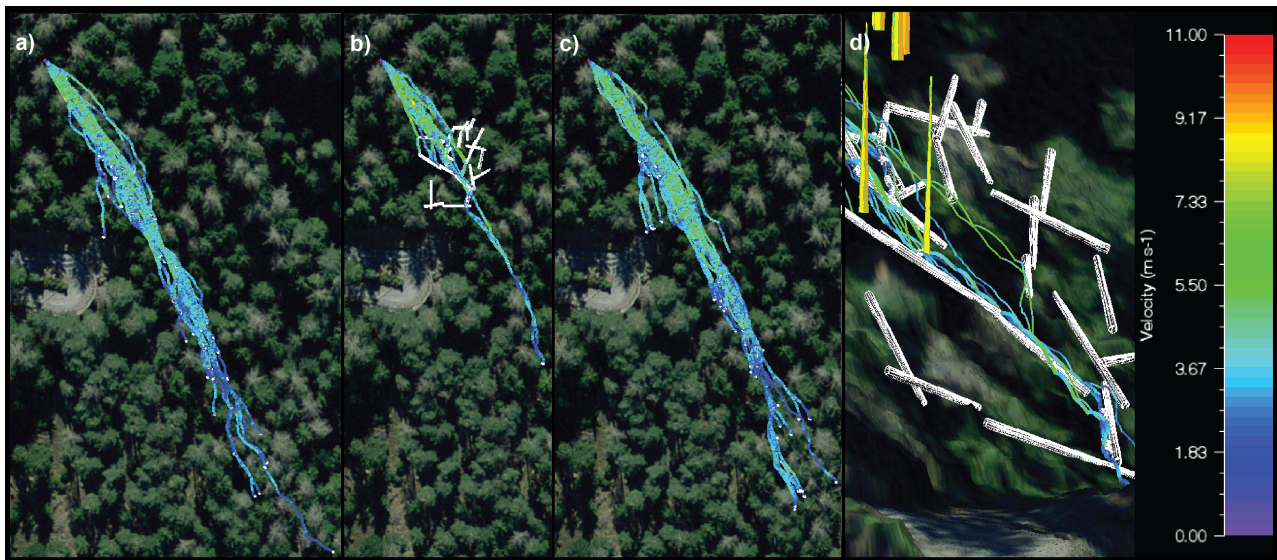
Figure 4. Velocity comparison of the 100 simulated rockfall trajectories in the a) ORG, b) DW and c) CLR states of the forest. d) Detailed three-dimensional view from above the forest road of the trajectories in b) within the deadwood section: lying deadwood in white, standing trees in yellow. Source of orthophoto (a - d): Federal Office of Topography

4 Discussion

The important effect of lying deadwood on the rockfall dynamics of 45 kg rocks is demonstrated by the presented experimental results. Although a certain rockfall protection effect by deadwood was known in practice, it has never been investigated with such a systematic, full-scale experiment. One out of 28 released rocks (3.6%) surpassed the piled deadwood section in the upper third of the experimental **DW** slope. Compared to **ORG** and **CLR** where 81.0% and 78.1% of the rocks passed the deadwood area, the deadwood stopping capacity due to the deadwood barrier effect within this shape class is substantial. Even if the GNSS-uncertainty is taken into account still 71.4% and 73.2% of the released rocks within the **ORG** and **CLR** set-ups reached the forest below the deadwood section. This is a main difference to the findings of Bourrier et al. (2012), where vast majority of the released rocks impacted the four felled deadwood trunks (85.7%), but only 8.5% of the rocks stopped immediately. The differences in experimental design and results underlines the assumption, that realistic deadwood configurations have a better protective function than deadwood with direct ground contact. The ratio between rock and deadwood log diameter might play an important role, both in terms of hindering rolling over of the obstacle as well as in terms of breaking prevention, as the reported ratio in Bourrier et al. (2012) < 1 and the here observed ratio > 1 imply. If the protective effect of deadwood is deliberately used as a silvicultural measure, we recommend to arrange logs on top of each other behind tree stumps (as discussed by Olmedo (2015); Olmedo et al. (2020)) in order to achieve a more favorable rock-to-deadwood diameter-ratio. Similar to the mean slope of Bourrier et al. (2012), the presented study site features an acceleration zone of roughly 37° but regrades in the deadwood area to 33°.

Although run out estimations with the shadow angle method have lost importance, since three dimensional rockfall simulations prevail, it is shown that this parameter is increased by the deadwood. As the amount of the absolute angle increase is strongly depended on the location of the deadwood section, which was in this study in the upper third, a general shadow-angle-reduction due to deadwood is not applicable.

According to the measured in situ data (Tab. 1), the states of the forest **ORG** and **CLR** with high maximal accelerations per run also showed higher mean velocities than **DW**. These measurements underlie the assumption that higher velocities increase the probability of harder impacts. Additionally, longer MROD and run times resulted in a higher probability of hitting hard ground material, especially when rocky sections are not randomly distributed across the study site and more frequent at the lowest part of the slope. This effect was not visible within the simulations, as for the whole area, one single ground parameter-set was used. This additionally explains why velocities of short trajectories (**DW**) are modeled more precisely as the velocities of trajectories with longer MROD (**ORG** and **CLR**). Locally higher M_e and lower C_d values could solve this issue. However, since the calibrated data should serve to model rockfall in similar forests, it is not debatable to include details down to the single rock scale.

The detected maximal rotational velocities per run are slightly higher within this campaign, as expected from the empirically derived mass - mean rotational velocity relationship from open field experiments (Caviezel et al., 2021). However, experimental and simulated results for rotational velocities differ substantially. While the standard deviations of the mean rotational velocities between the experiments and the simulations overlap at least for two (**DW** and **CLR**) of the three forestal states, no overlap

is given for the maximal rotational velocities per run. Nevertheless, these maximal rotational velocities show a distinctly higher standard deviation than the simulated and the mean values. This might corroborate the considerable influence of local disparities in soil and tree conditions, leading to a higher acting torque-variability on the rocks, resulting in higher maximal rotational velocities.

The **DW** sensor streams feature less FI per run than the other two states. As most of the rocks stopped within the deadwood section, a higher ratio of impacts was expected. Surprisingly, the mean number of frontal impact per run lies well below 50 %. Hence, the stopping process in the deadwood section is not abrupt enough to classify as frontal impact like the hit of a standing tree. Additional clarification can be offered, if the FI are evaluated as frontal impacts per runtime ($\text{FI} \cdot \text{s}^{-1}$). (Tab. 1): Even if the **ORG** state still has the highest $\text{FI} \cdot \text{s}^{-1}$, the **CLR** state shows slightly lower values than the **DW** state. The shortest mean runtime implies the smallest possibility to experience FI in the deadwood state. This is not outweighed by the stopping process within the deadwood, in particular because it apparently features a more complex, temporally stretched, behavior. Although without visual verification not all questions concerning the influence of rotational velocities on FI can be solved, Figure 3.b) illustrates, that solely acceleration data would perform worse: Of the three impacts with $\geq 10 \ \text{m} \cdot \text{s}^{-2}$, the first two impacts entail increasing rotational velocities, which seems unlikely for FI on an opposing object. The third impact, however, is related to a severe drop of the rotational velocity. Compared with the overall measured accelerations of the **CLR** state (Fig. 3.c), the **DW**-impacts (Fig. 3.b) are much softer, but comparable with the impacts of **CLR** in the corresponding time range, and thus slope area. This consolidates the assumption that acceleration data feature dependencies regarding the soil characteristics and that therefore the used, on gyroscopic data based FI detection-method seems to be more convenient. The FI of the depicted sensor streams in Figure 3 shows a reduction by more than 50 % from > 40 rad ($> 2000° \cdot \text{s}^{-1}$) to <20 rad ($< 1000° \cdot \text{s}^{-1}$), while the corresponding accelerations differ with values ranging from $15.0 \ \text{m} \cdot \text{s}^{-2}$ to $46.9 \ \text{m} \cdot \text{s}^{-2}$ by more than 300 %. The FI detection within the simulations based on the same thresholds was not possible, due to the used and recommended standard computational output time-step of 0.02, which is compared to the 1 kHz sampling rate of the StoneNode sensors too low.

The protective effect of lying deadwood can only be emulated by rockfall simulations if deadwood configurations can be added realistically into the code. Here, all three states of the forest, incorporating the exact GNSS position as three-dimensional cones for standing and lying trees alike could be reconstructed as input scenario for the rockfall simulations. This strict adherence to realistic site conditions enhance the significance of the model output for hazard assessment significantly. The inclusion of the deadwood logs as three dimensional cones, resulted in simulations with a realistic deposition pattern. Apart from the depicted barrier effect of single, near-slope deadwood logs, piled trunks after wind-throw events can now be incorporated into simulations. Additionally, a tunnel effect can be modeled: rocks can slip under deadwood, which is essential or if the deadwood branches are still fresh and support the log above ground. In such cases, other methods like adapting the slope in the corresponding grid cells, overestimate the deadwood effect and experience drawbacks (Fuhr et al., 2015; Costa et al., 2021).

Nevertheless, the simulations do not feature the observed experimental lateral spread. A possible explanation lies in the post-experimental timing of the LiDAR flight: the deadwood clearing work may have changed the local topography slightly, which was during the **ORG** and **DW** experiments partially responsible for the lateral spread, since the CLR_{FIT} generally fits best for all soil parameters-sets.

One possible explanation of the overestimated mean runtimes in the simulations (Tab. 1) could be caused by a critical issue with any numeric rockfall code: an accurate stopping criterion. This criterion describes the minimal total kinetic energy of the rock below which the simulation is stopped. To examine the contribution to this overestimation, we calculated the mean velocity on the last 2 m of travelling distance ($\mathrm{ORG_{v-stop}}$ and $\mathrm{CLR_{v-stop}}$), as the rocks could theoretically move with a very low velocity slightly above the stopping criterion (= 0.5 m·s^{-1}) for several seconds and distort the mean velocity value. However, this was not observed, as $\mathrm{ORG_{v-stop}} = 1.5 \pm 0.4$ and $\mathrm{CLR_{v-stop}} = 1.3 \pm 0.4 \mathrm{m \cdot s^{-1}}$ are distinctly higher than the stopping criterion. From this we conclude that the stopping process of the rocks is simulated close to reality. Consequently, we deduce that the translational velocity is slightly underestimated over longer distances. The accurate treatment of the entire deceleration phase of rocks represents a demanding challenge for any rockfall code, in particular in this low weight class regime. In the given experimental set-up the runtimes solely determine the mean rock velocity and thus the translational kinetic energy, the most crucial output variable of rockfall simulation programs. Hence, four main limitations came to our attention during the study, which leads to new practically relevant follow-up research questions and hypotheses, and should be included in future experimental campaigns:

1. The investigated rock mass of 45 kg represents in many stratigraphic units a common rockfall release volume with a high occurrence probability and small return period. Nevertheless, with energies ≤ 3 kJ only low rockfall intensities are achieved (FOEN, 2016). The verification of the rockfall stopping capacity under higher energies remains to be investigated.

2. For an in depth rockfall-model-calibration in forests, such a deposition pattern in different states of the forest is unique and allowed to examine the performance of the presented three dimensional deadwood in rockfall simulations. The in situ measurement data available beyond the deposition pattern fostered helps for a complete calibration. However, the evaluations showed that (for example) a visual check of the impact location at high acceleration measurement values is desirable. Although challenging due to the visibility restrictions because of the trees (Bourrier et al., 2012), a slope-wide reconstruction of the rock velocities would complete the set of the parameters of interest (Caviezel et al., 2019a). Developments towards automated detection of tree impacts of in situ sensor data, visually coverage is necessary to gain a large enough amount of data.

3. Only compact rock shapes (Sneed and Folk, 1958) were used in this study. The results of open land experiments emphasize the importance of different rock shapes (Caviezel et al., 2021). Investigation on rockfall simulations in forests incorporating different rock shapes (Lu et al., 2020) show the importance of real scale experiments as calibration basis as different contact behavior and MROD are expected.

4. The fresh deadwood used here originates from trees felled on site. However, for forestry practice, it is also relevant to know how decomposed deadwood protects against rockfall, how this effect is changing over time. It is essential to understand the potential adverse long-term effects of rocks deposited temporarily behind decaying deadwood as they may act as secondary rockfall sources.

255 Despite these still existing limitations and open questions, our results indicate that the complete removal of lying deadwood after natural disturbances or logging operations can lead to a substantial decrease in rockfall protection. While our experiments allow also to quantify such effects, more experiments and long-term studies are needed to fully quantify them for different settings and to optimise their implementation in rockfall simulation models and management guidelines.

5 Conclusions

260 This experimental rockfall trilogy with 45 kg, cubic shaped rocks within different states of the forest, highlights the high protection capacity of partly piled deadwood against low-energy rockfalls. This is of general interest, as natural disturbances causing piled deadwood are suggested to increase in future. The ratio between the rock diameter and the overall deadwood height might have a decisive impact on the rock stopping capacity, whose thorough quantification needs further research. The agreement achieved between the simulations and the experiments is particularly convincing for the mean runout distance, while
265 it somewhat underestimates the lateral dispersion of the deposition points. The presented three-dimensional deadwood logs within the simulations performed realistic which affirms the demand for the inclusion of deadwood in rockfall simulations. This will allow forest managers to base their future dead wood management after natural disturbances, thinning, sanitary felling and regeneration cuts on a larger scientific basis. Based on our experimental results, we recommend at least in the case of relatively small expected rock sizes with low deadwood log breakage probability to consider supplementing the natural
270 protection of the ecological infrastructure with additional transverse, lying deadwood logs as a cost-effective, economical, ecological, nature based protection measure. Thanks to the extended model outcomes presented here, the benefits of these measures can be evaluated and thus planned in a more systematic manner, which in turn could reduce the overall economic costs. Future studies should focus on higher rockfall energies, where the rock velocities are completely retrievable, the influence of the rock shape is in depth examined and long-term effects after partial decay of deadwood in post-disturbance stands is taken
275 into account.

Data availability. The experimental deposition points, the in situ StoneNode data and the FI-detection $Matlab$ script as well as the used input data for the rockfall simulation (DEM, tree file, release point and .rts files of the trees) will be public available under doi:10.16904/envidat.248 upon publication acceptance.

Author contributions. AR performed the data analysis, conceived the simulations and wrote the manuscript based on discussions and im-
280 provements from all authors, ES, AC, AR carried out the model calibration, AC conceived the experiment. AC, YB, KS, SD, AS carried out the experiments. KS, MK and DM conducted the forest inventory. YB and AS operated the GNSS and GL and MC programmed the deadwood Module.

Competing interests. The authors declare that they have no conflict of interest.

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