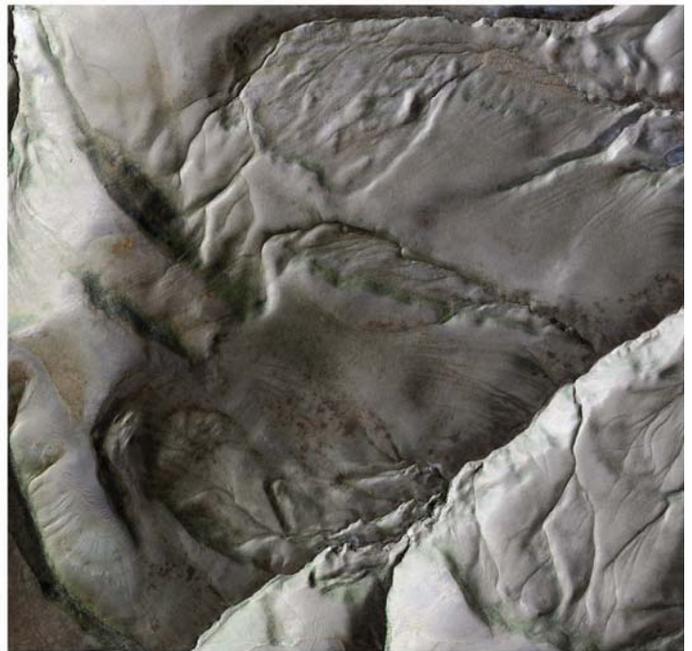# LiDAR REMOTE SENSING
KITTITAS & RATTLESNAKE STUDY AREAS

(KITTITAS – COLOKUM : 2/7/2011)
(RATTLESNAKE : 3/18/2011)

PUGET SOUND REGIONAL COUNCIL
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LiDAR Remote Sensing Data Collection:
# Kittitas, WA – Colockum & Rattlesnake Study Areas

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1. Overview

Watershed Sciences, Inc. (WSI) collected Light Detection and Ranging (LiDAR) data on six days between September 15th and November 5th, and from November 6th – 13th, 2010 for the Puget Sound LiDAR Consortium. This report documents the data acquisition, processing methods, accuracy assessment, and deliverables for the Colockum and Rattlesnake areas of interest (AOIs) in Kittitas & Benton Counties, WA. The requested areas were expanded to include a 100m buffer to ensure complete coverage and adequate point densities around survey area boundaries. As the Colockum dataset is adjacent to a previously delivered LiDAR dataset (Wenatchee), comparisons were made to ensure spatial accuracy between datasets. The total acreage of the Colockum AOI is 172,115 acres. The total acreage of the Rattlesnake AOI is 184,359 acres. (Figure 1)

Figure 1. Colockum and Rattlesnake areas of interest, Washington.
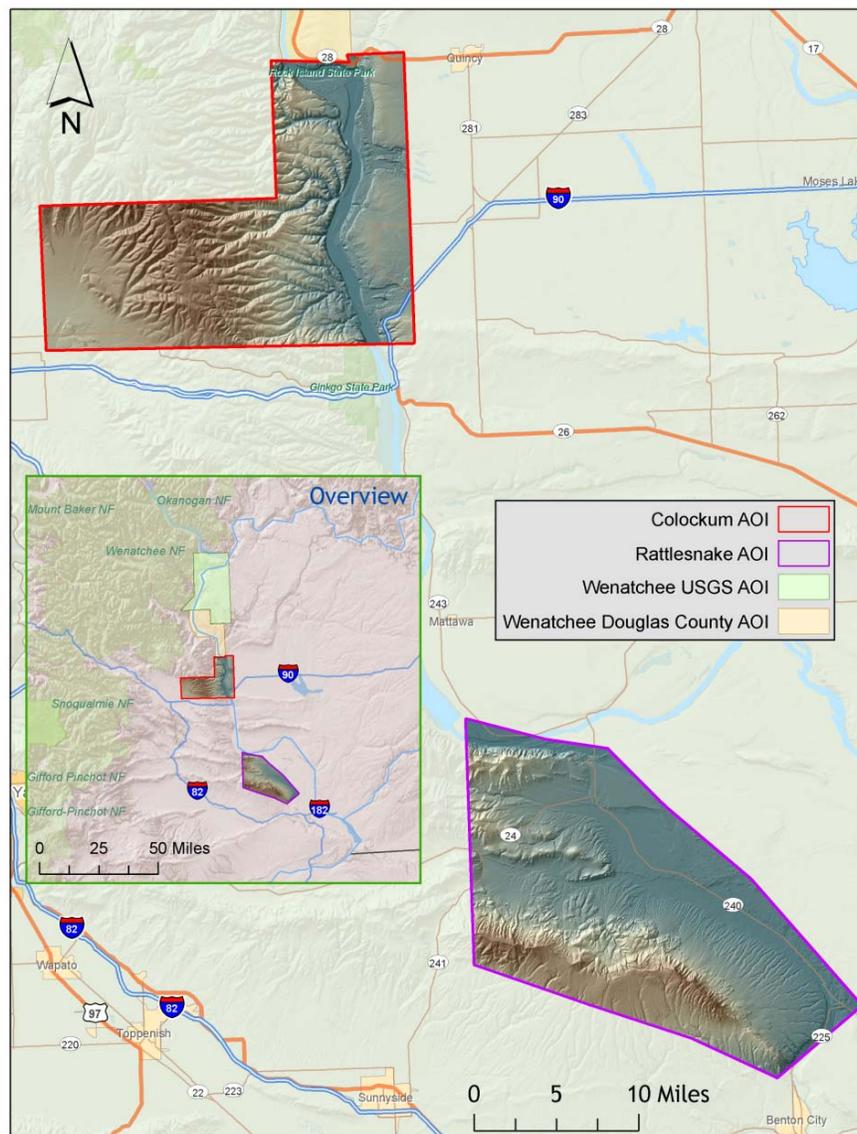
2. Acquisition

2.1 Airborne Survey – Instrumentation and Methods

The LiDAR survey utilized Leica ALS50 Phase II and ALS 60 sensors in a Cessna Caravan 208B (dual-mounted 9/15/10). The sensors operate with Automatic Gain Control (AGC) for intensity correction.   Depending on acquisition day, weather, and terrain, the Leica systems were set to acquire from ≥83,000 to 105,900 laser pulses per second (i.e., 83 – 105.9 kHz pulse rate) and flown at 900-1300 meters above ground level (AGL), capturing a scan angle of ±14° from nadir. These settings were developed to yield points with an average native pulse density of ≥8 pulses per square meter over terrestrial surfaces. It is not uncommon for some types of surfaces (e.g. dense vegetation or water) to return fewer pulses than the laser originally emitted. These discrepancies between 'native' and 'delivered' density will vary depending on terrain, land cover, and the prevalence of water bodies.

The Cessna Caravan is a stable platform, ideal for flying slow and low for high density projects. The Leica ALS50 sensor head installed in the Caravan is shown on the left.

All areas were surveyed with an opposing flight line side-lap of ≥50% (≥100% overlap) to reduce laser shadowing and increase surface laser painting. The Leica laser systems allow up to four range measurements (returns) per pulse, and all discernable laser returns were processed for the output dataset.

To accurately solve for laser point position (geographic coordinates x, y, z), the positional coordinates of the airborne sensor and the attitude of the aircraft were recorded continuously throughout the LiDAR data collection mission. Aircraft position was measured twice per second (2 Hz) by an onboard differential GPS unit. Aircraft attitude was measured 200 times per second (200 Hz) as pitch, roll and yaw (heading) from an onboard inertial measurement unit (IMU). To allow for post-processing correction and calibration, aircraft/sensor position and attitude data are indexed by GPS time.

2.2 Ground Survey – Instrumentation and Methods

During the LiDAR survey, static (1 Hz recording frequency) ground surveys were conducted over set monuments. Monument coordinates are provided in Table 1 and shown in Figures 2 & 3 for the AOIs. After the airborne survey, the static GPS data are processed using triangulation with Continuously Operating Reference Stations (CORS) and checked using the Online Positioning User Service (OPUS[1]) to quantify daily variance. Multiple sessions are processed over the same monument to confirm antenna height measurements and reported position accuracy.

Indexed by time, these GPS data are used to correct the continuous onboard measurements of aircraft position recorded throughout the mission. Control monuments were located within 13 nautical miles of the survey area.

Trimble GPS equipment in the Colockum study area.

2.2.1 Instrumentation

Trimble GPS equipment in the Rattlesnake study area.

For these study areas, a Trimble GPS receiver model R7 with Zephyr Geodetic antenna with ground plane was deployed for all static control   A Trimble model R8 GNSS unit was used for collecting check points using real time kinematic (RTK) survey techniques. For RTK data, the collector begins recording after remaining stationary for 5 seconds then calculating the pseudo range position from at least three epochs with the relative error under 1.5 cm horizontal and 2 cm vertical. All GPS measurements are made with dual frequency L1-L2 receivers with carrier-phase correction.

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[1] Online Positioning User Service (OPUS) is run by the National Geodetic Survey to process corrected monument positions.

LiDAR Data Acquisition and Processing: Kittitas, WA – Colockum & Rattlesnake Study Areas

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2.2.2 Monumentation

Watershed Sciences established ten new monuments (Table 1) and occupied a NGS monument (B317). The Watershed Sciences' monumentation was implemented with 5/8" x 30" rebar topped with a metal cap stamped with the project ID and year. Monuments selected were found to have good visibility and optimal location to support a LiDAR Acquisition flight. Chris Yotter-Brown (WA-PLS #46328) Watershed Sciences' staff surveyor provided professional supervision and oversight to all survey aspects of this project.

Table 1. Base Station control coordinates for the Kittitas LiDAR data collection (Colockum & Rattlesnake study areas)

Base Station ID	Datum: NAD83 (CORS96)		GRS80
	Latitude	Longitude	Ellipsoid Z (meters)
KIT_01	46° 59' 36.73978" N	120° 17' 15.91698" W	644.816
KIT_02	47° 00' 03.15237" N	120° 18' 34.82012" W	618.239
KIT_03	47° 02' 06.89806" N	120° 21' 51.03535" W	581.669
KIT_04	47° 04' 49.08095" N	120° 22' 11.90529" W	703.872
KIT_05	47° 04' 00.59276" N	120° 00' 05.04248" W	361.938
KIT_06	47° 04' 22.55337" N	119° 57' 11.48711" W	385.076
RTLSNK1	46° 32' 17.70901" N	119° 51' 36.97558" W	425.626
B317	46° 34' 39.12106" N	119° 43' 38.83744" W	222.054
RTLSNK2	46° 29' 58.20746" N	119° 36' 36.77332" W	161.285
RTLSNK3	46° 30' 21.50515" N	119° 37' 44.11283" W	167.799
RTLSNK4	46° 22' 58.32839" N	119° 25' 31.06945" W	127.510

2.2.3 Methodology

Each aircraft is assigned a ground crew member with two Trimble R7 receivers and an R8 receiver. The ground crew vehicles are equipped with standard field survey supplies and equipment including safety materials. All control monuments are observed for a minimum of one survey session lasting no fewer than 4 hours and another session lasting no fewer than 2 hours. At the beginning of every session the tripod and antenna are reset, resulting in two

independent instrument heights and data files. Data is collected at a rate of 1Hz using a 10 degree mask on the antenna.

The ground crew uploads the GPS data to our online Dropbox site on a daily basis to be returned to the office for Professional Land Surveyor (PLS) oversight, QA/QC review, and processing. OPUS processing triangulates the monument position using 3 CORS stations resulting in a fully adjusted position. After multiple days of data have been collected at each monument, accuracy and error ellipses are calculated from the OPUS reports. This information leads to a rating of the monument based on FGDC-STD-007.2-1998[2] at the 95% confidence level. When a statistically stable position is found CORPSCON[3] 6.0.1 software is used to convert the UTM positions to geodetic positions. This geodetic position is used for processing the LiDAR data.

RTK and aircraft mounted GPS measurements are made during periods with PDOP[4] less than or equal to 3.0 and with at least 6 satellites in view of both a stationary reference receiver and the roving receiver. Static GPS data collected in a continuous session average the high PDOP into the final solution in the method used by CORS stations. RTK positions are collected on bare earth locations such as paved, gravel or stable dirt roads, and other locations where the ground is clearly visible (and is likely to remain visible) from the sky during the data acquisition and RTK measurement period(s). RTK measurements are not taken on highly reflective surfaces such as center line stripes or lane markings on roads. RTK points were taken no closer than one meter to any nearby terrain breaks such as road edges or drop offs.

Trimble GPS survey equipment configured for RTK collection

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[2] Federal Geographic Data Committee Draft Geospatial Positioning Accuracy Standards (Part 2 table 2.1)
[3] U.S. Army Corps of Engineers , Engineer Research and Development Center Topographic Engineering Center software
[4] PDOP: Point Dilution of Precision is a measure of satellite geometry, the smaller the number the better the geometry between the point and the satellites.

LiDAR Data Acquisition and Processing: Kittitas, WA – Colockum & Rattlesnake Study Areas

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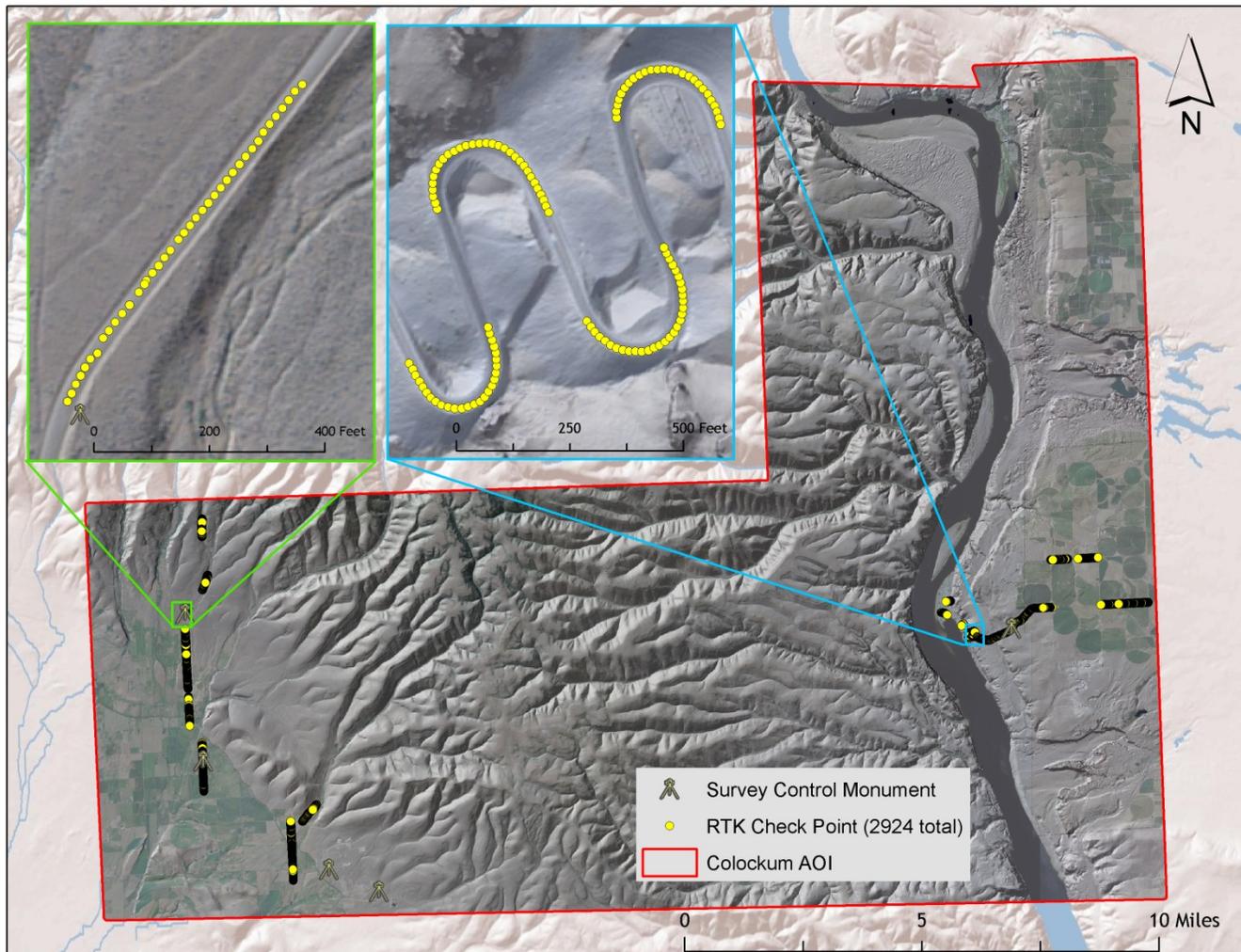*Figure 2. RTK check point and control monument locations used in the Colockum AOI*
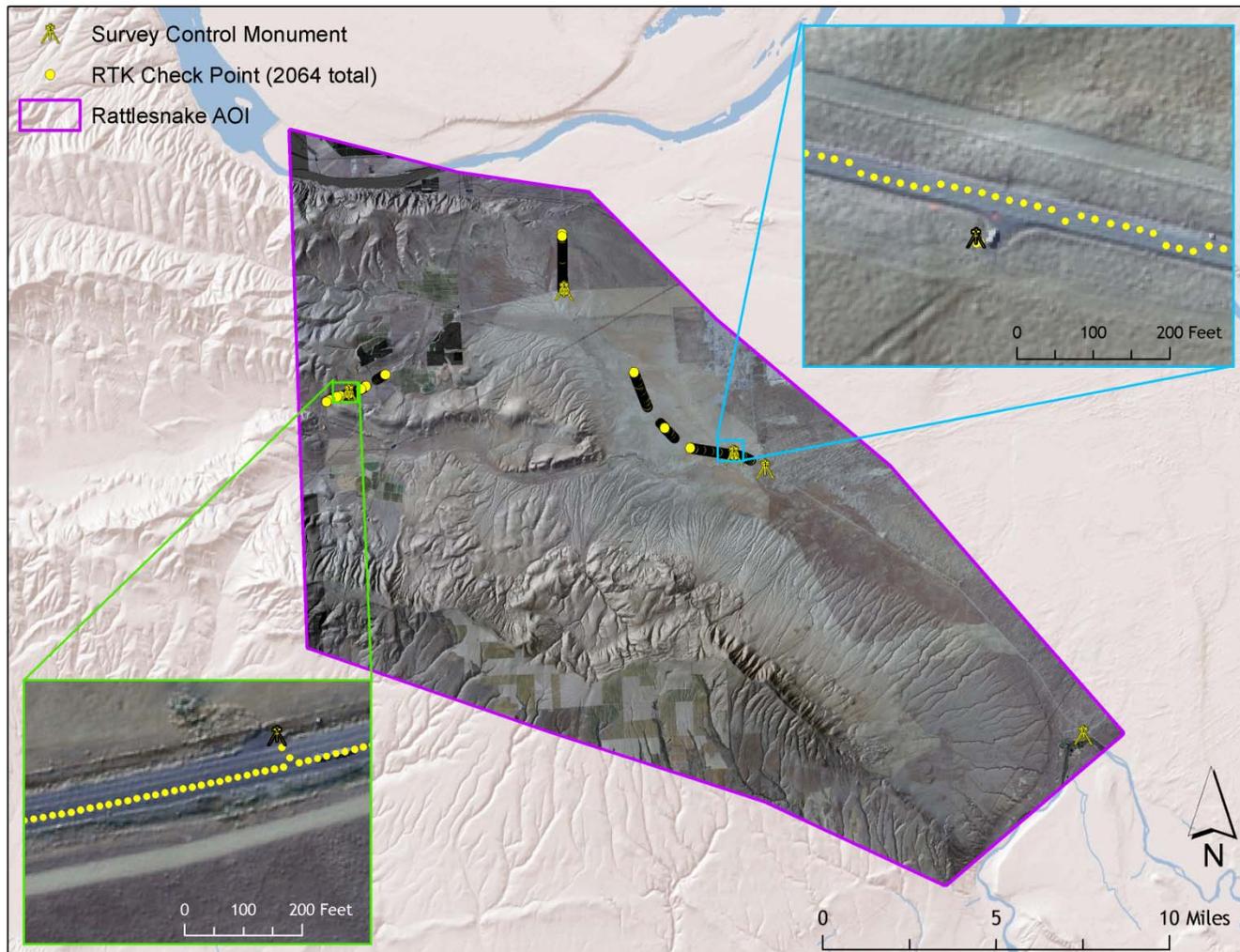
Figure 3. RTK check point and control monument locations used in the Rattlesnake AOI

Legend:
- Survey Control Monument
- RTK Check Point (2064 total)
- Rattlesnake AOI

3. LiDAR Data Processing

3.1 Applications and Work Flow Overview

1. Resolved kinematic corrections for aircraft position data using kinematic aircraft GPS and static ground GPS data.
   Software: Waypoint GPS v.8.10, Trimble Geomatics Office v.1.62

2. Developed a smoothed best estimate of trajectory (SBET) file that blends post-processed aircraft position with attitude data. Sensor head position and attitude were calculated throughout the survey. The SBET data were used extensively for laser point processing.
   Software: IPAS v.1.35

3. Calculated laser point position by associating SBET position to each laser point return time, scan angle, intensity, etc. Created raw laser point cloud data for the entire survey in *.las (ASPRS v. 1.2) format.
   Software: ALS Post Processing Software v.2.70

4. Imported raw laser points into manageable blocks (less than 500 MB) to perform manual relative accuracy calibration and filter for pits/birds. Ground points were then classified for individual flight lines (to be used for relative accuracy testing and calibration).
   Software: TerraScan v.10.009

5. Using ground classified points per each flight line, the relative accuracy was tested. Automated line-to-line calibrations were then performed for system attitude parameters (pitch, roll, heading), mirror flex (scale) and GPS/IMU drift. Calibrations were performed on ground classified points from paired flight lines. Every flight line was used for relative accuracy calibration.
   Software: TerraMatch v.10.006

6. Position and attitude data were imported. Resulting data were classified as ground and non-ground points.   Statistical absolute accuracy was assessed via direct comparisons of ground classified points to ground RTK survey data. Data were then converted to orthometric elevations (NAVD88) by applying a Geoid03 correction.
   Software: TerraScan v.10.009, TerraModeler v.10.004

7. Bare Earth models were created as a triangulated surface and exported as ArcInfo ASCII grids at a 3-foot pixel resolution. Highest Hit models were created for any class at 3-foot grid spacing and exported as ArcInfo ASCII grids.
   Software: TerraScan v.10.009, ArcMap v. 9.3.1, TerraModeler v.10.004

3.2 Aircraft Kinematic GPS and IMU Data

LiDAR survey datasets were referenced to the 1 Hz static ground GPS data collected over pre-surveyed monuments with known coordinates. While surveying, the aircraft collected 2 Hz kinematic GPS data, and the onboard inertial measurement unit (IMU) collected 200 Hz aircraft attitude data. Waypoint GPS v.8.10 was used to process the kinematic corrections for the aircraft. The static and kinematic GPS data were then post-processed after the survey to obtain an accurate GPS solution and aircraft positions. IPAS v.1.35 was used to develop a trajectory file that includes corrected aircraft position and attitude information. The trajectory data for the entire flight survey session were incorporated into a final smoothed best estimated trajectory (SBET) file that contains accurate and continuous aircraft positions and attitudes.

3.3 Laser Point Processing

Laser point coordinates were computed using the IPAS and ALS Post Processor software suites based on independent data from the LiDAR system (pulse time, scan angle), and aircraft trajectory data (SBET). Laser point returns (first through fourth) were assigned an associated (x, y, z) coordinate along with unique intensity values (0-255). The data were output into large LAS v. 1.2 files with each point maintaining the corresponding scan angle, return number (echo), intensity, and x, y, z (easting, northing, and elevation) information.

These initial laser point files were too large for subsequent processing. To facilitate laser point processing, bins (polygons) were created to divide the dataset into manageable sizes (< 500 MB). Flightlines and LiDAR data were then reviewed to ensure complete coverage of the survey area and positional accuracy of the laser points.

Laser point data were imported into processing bins in TerraScan, and manual calibration was performed to assess the system offsets for pitch, roll, heading and scale (mirror flex). Using a geometric relationship developed by Watershed Sciences, each of these offsets was resolved and corrected if necessary.

LiDAR points were then filtered for noise, pits (artificial low points), and birds (true birds as well as erroneously high points) by screening for absolute elevation limits, isolated points and height above ground. Each bin was then manually inspected for remaining pits and birds and spurious points were removed. In a bin containing approximately 7.5-9.0 million points, an average of 50-100 points are typically found to be artificially low or high.   Common sources of non-terrestrial returns are clouds, birds, vapor, haze, decks, brush piles, etc.

Internal calibration was refined using TerraMatch. Points from overlapping lines were tested for internal consistency and final adjustments were made for system misalignments (i.e., pitch, roll, heading offsets and scale). Automated sensor attitude and scale corrections yielded 3-5 cm improvements in the relative accuracy. Once system misalignments were corrected, vertical GPS drift was then resolved and removed per flight line, yielding a slight improvement (<1 cm) in relative accuracy.

The TerraScan software suite is designed specifically for classifying near-ground points (Soininen, 2004). The processing sequence began by 'removing' all points that were not 'near' the earth based on geometric constraints used to evaluate multi-return points. The

resulting bare earth (ground) model was visually inspected and additional ground point modeling was performed in site-specific areas to improve ground detail. This manual editing of ground often occurs in areas with known ground modeling deficiencies, such as: bedrock outcrops, cliffs, deeply incised stream banks, and dense vegetation. In some cases, automated ground point classification erroneously included known vegetation (i.e., understory, low/dense shrubs, etc.). These points were manually reclassified as default. Ground surface rasters were then developed from triangulated irregular networks (TINs) of ground points.

4. LiDAR Accuracy Assessment

4.1 Laser Noise and Relative Accuracy

Laser Noise
For any given target, laser noise is the breadth of the data cloud per laser return (i.e., last, first, etc.). Lower intensity surfaces (roads, rooftops, still/calm water) experience higher laser noise.

Relative Accuracy
Relative accuracy refers to the internal consistency of the data set - the ability to place a laser point in the same location over multiple flight lines, GPS conditions, and aircraft attitudes. Affected by system attitude offsets, scale, and GPS/IMU drift, internal consistency is measured as the divergence between points from different flight lines within an overlapping area. Divergence is most apparent when flight lines are opposing. When the LiDAR system is well calibrated, the line-to-line divergence is low (<10 cm). See Appendix A for further information on sources of error and operational measures that can be taken to improve relative accuracy.

Relative Accuracy Calibration Methodology
1. <u>Manual System Calibration</u>: Calibration procedures for each mission require solving geometric relationships that relate measured swath-to-swath deviations to misalignments of system attitude parameters. Corrected scale, pitch, roll and heading offsets were calculated and applied to resolve misalignments. The raw divergence between lines was computed after the manual calibration was completed and reported for each survey area.
2. <u>Automated Attitude Calibration</u>: All data were tested and calibrated using TerraMatch automated sampling routines. Ground points were classified for each individual flight line and used for line-to-line testing. System misalignment offsets (pitch, roll and heading) and scale were solved for each individual mission and applied to respective mission datasets. The data from each mission were then blended when imported together to form the entire area of interest.
3. <u>Automated Z Calibration</u>: Ground points per line were used to calculate the vertical divergence between lines caused by vertical GPS drift. Automated Z calibration was the final step employed for relative accuracy calibration.

4.2 Absolute Accuracy

To minimize the contributions of laser noise and relative accuracy to absolute error, a number of noise filtering and calibration procedures were performed prior to evaluating absolute accuracy. The LiDAR quality assurance process uses the data from the real-time kinematic (RTK) ground survey conducted in the AOI. For the Colockum and Rattlesnake study areas a total of 2924 and 2064 RTK GPS measurements were collected respectively on hard surfaces distributed among multiple flight swaths. To assess absolute accuracy the location coordinates of these known RTK ground points were compared to those calculated for the closest ground-classified laser points.

The vertical accuracy of the LiDAR data is described as the mean and standard deviation (sigma ~ σ) of divergence of LiDAR point coordinates from RTK ground survey point coordinates. To provide a sense of the model predictive power of the dataset, the root mean square error (RMSE) for vertical accuracy is also provided. These statistics assume the error distributions for x, y, and z are normally distributed, thus we also consider the skew and kurtosis of distributions when evaluating error statistics.

Statements of statistical accuracy apply to fixed terrestrial surfaces only and may not be applied to areas of dense vegetation or steep terrain (See Appendix A).

5. Study Area Results

Summary statistics for point resolution and accuracy (relative and absolute) of the Colockum and Rattlesnake LiDAR data collected in Kittitas and Benton Counties, WA are presented below in terms of central tendency, variation around the mean, and the spatial distribution of the data (for point resolution by tile).

5.1 Data Summary

Table 2. LiDAR Resolution and Accuracy - Specifications and Achieved Values.

Colockum:

	Targeted	Achieved
Resolution:	≥ 8 points/m^2	8.5 points/m^2 (0.79 points/ft^2)
Vertical Accuracy (1 σ):	<15 cm	3.1 cm (0.10 ft)

Rattlesnake:

	Targeted	Achieved
Resolution:	≥ 8 points/m^2	8.3 points/m^2 (0.77 points/ft^2)
Vertical Accuracy (1 σ):	<15 cm	3.6 cm (0.12 ft)

5.2 Data Density/Resolution

The average first-return density of the delivered datasets are 8.5 points per square meter for the Colockum study area and 8.3 points per square meter for the Rattlesnake study area (Table 2). The initial datasets, acquired to be ≥8 points per square meter, were filtered as described previously to remove spurious or inaccurate points. Additionally, some types of surfaces (i.e., dense vegetation, breaks in terrain, water, steep slopes) may return fewer pulses (delivered density) than the laser originally emitted (native density).

Ground classifications were derived from automated ground surface modeling and manual, supervised classifications where it was determined that the automated model had failed. Ground return densities will be lower in areas of dense vegetation, water, or buildings.

Figures 8-11 show the distribution of average native and ground point densities for each processing tile.

Cumulative LiDAR data resolution for the Colockum AOI:

- Average Point (First Return) Density = 0.79 points/ft^2 (8.5 points/m^2)
- Average Ground Point Density = 0.30 points/ft^2 (3.3 points/m^2)

Cumulative LiDAR data resolution for the Rattlesnake AOI:

- Average Point (First Return) Density = 0.77 points/ft^2 (8.3 points/m^2)
- Average Ground Point Density = 0.40 points/ft^2 (4.3 points/m^2)

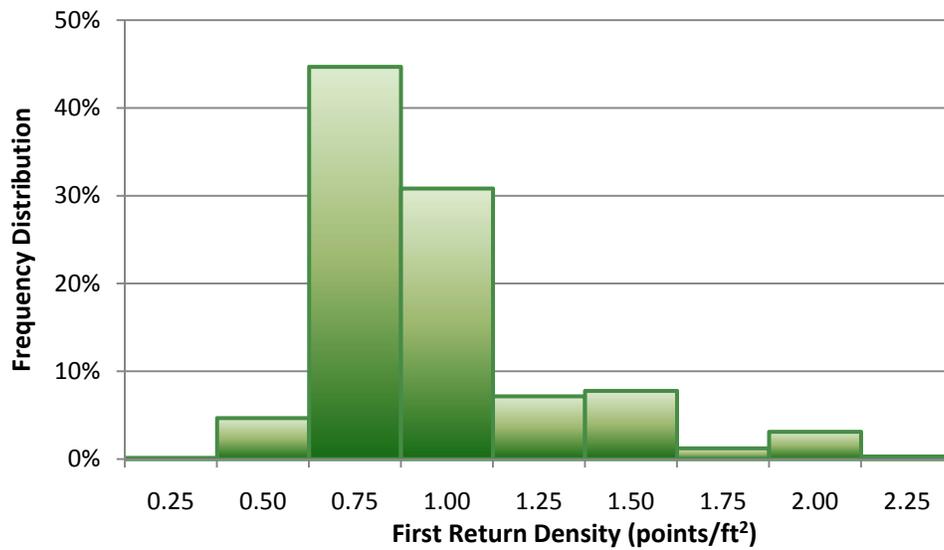*Figure 4. Density distribution for first return laser points in the Colockum AOI.*

Figure 5. Density distribution for first return laser points in the Rattlesnake AOI.

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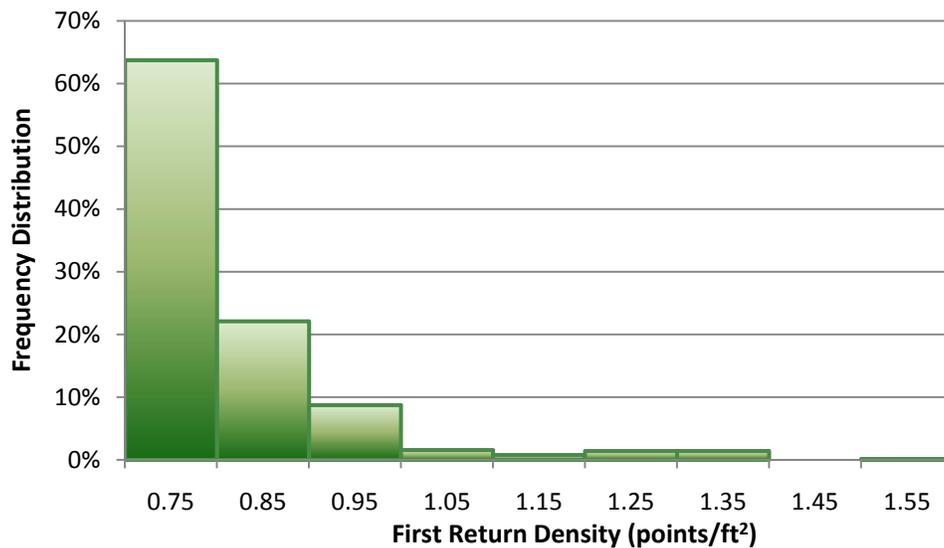
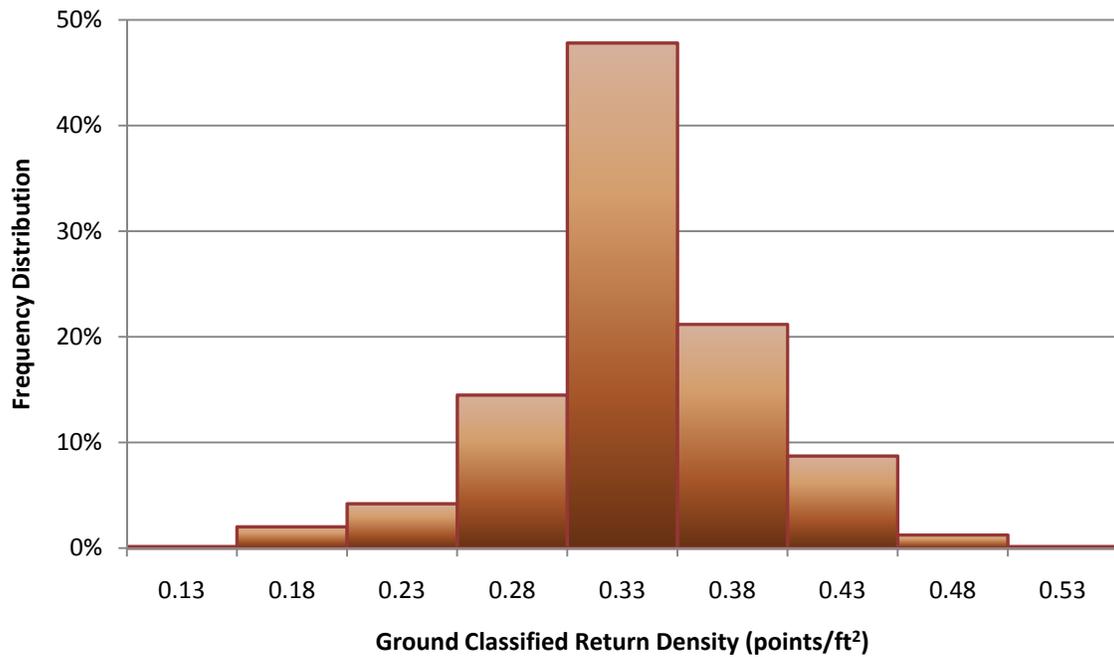*Figure 6. Density distribution for ground classified laser points in the Colockum AOI.*

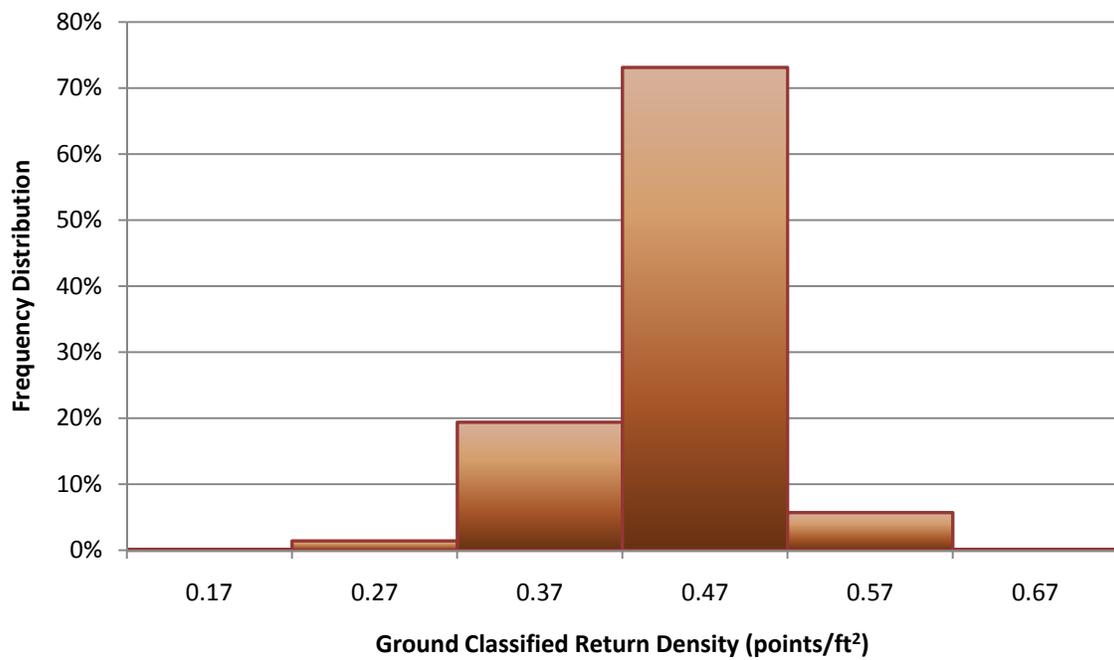*Figure 7. Density distribution for ground classified laser points in the Rattlesnake AOI.*

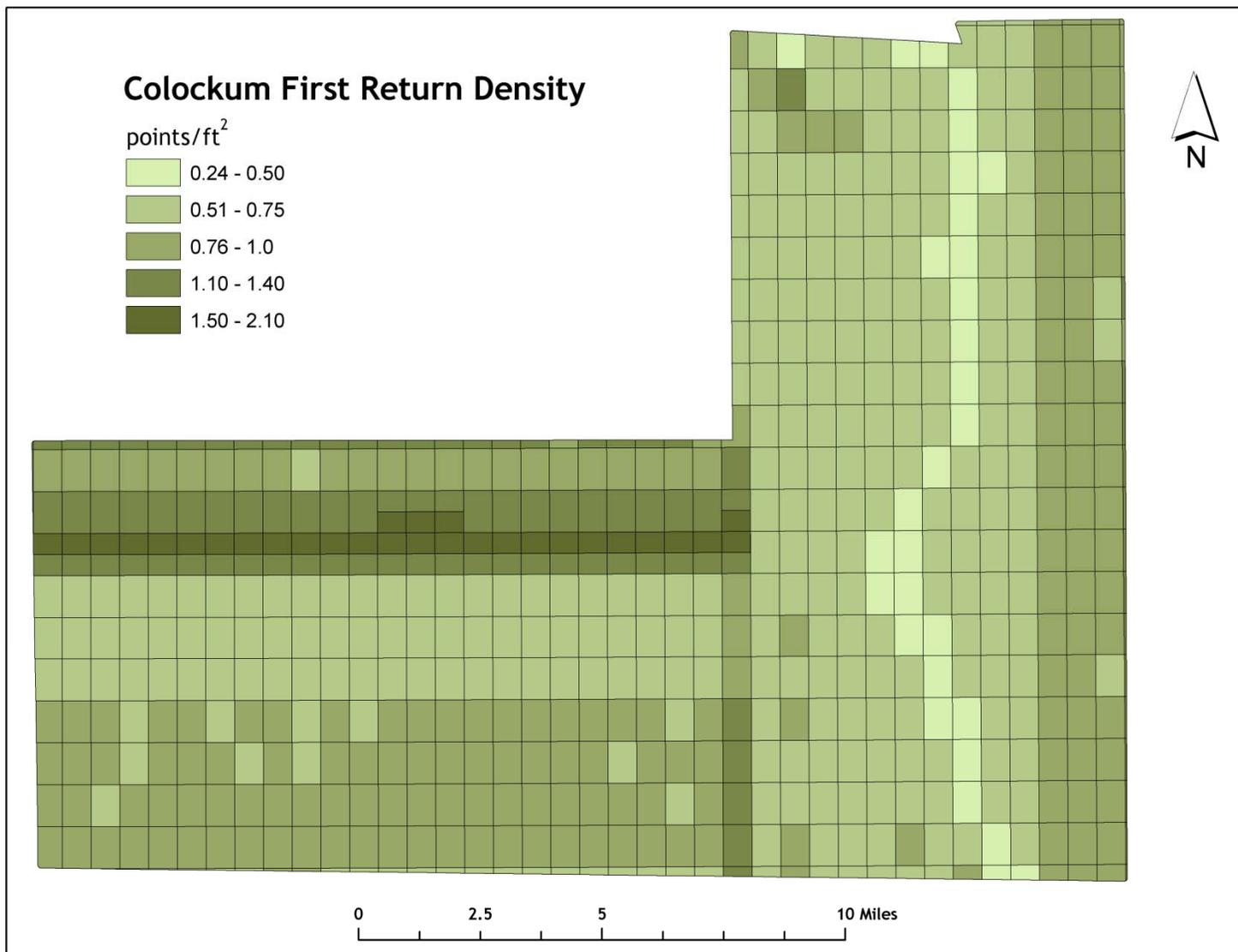*Figure 8.* First Return density for the *Colockum* AOI by 1/100th USGS tile.

Figure 9. *Ground density for the **Colockum** AOI by 1/100th USGS tile*
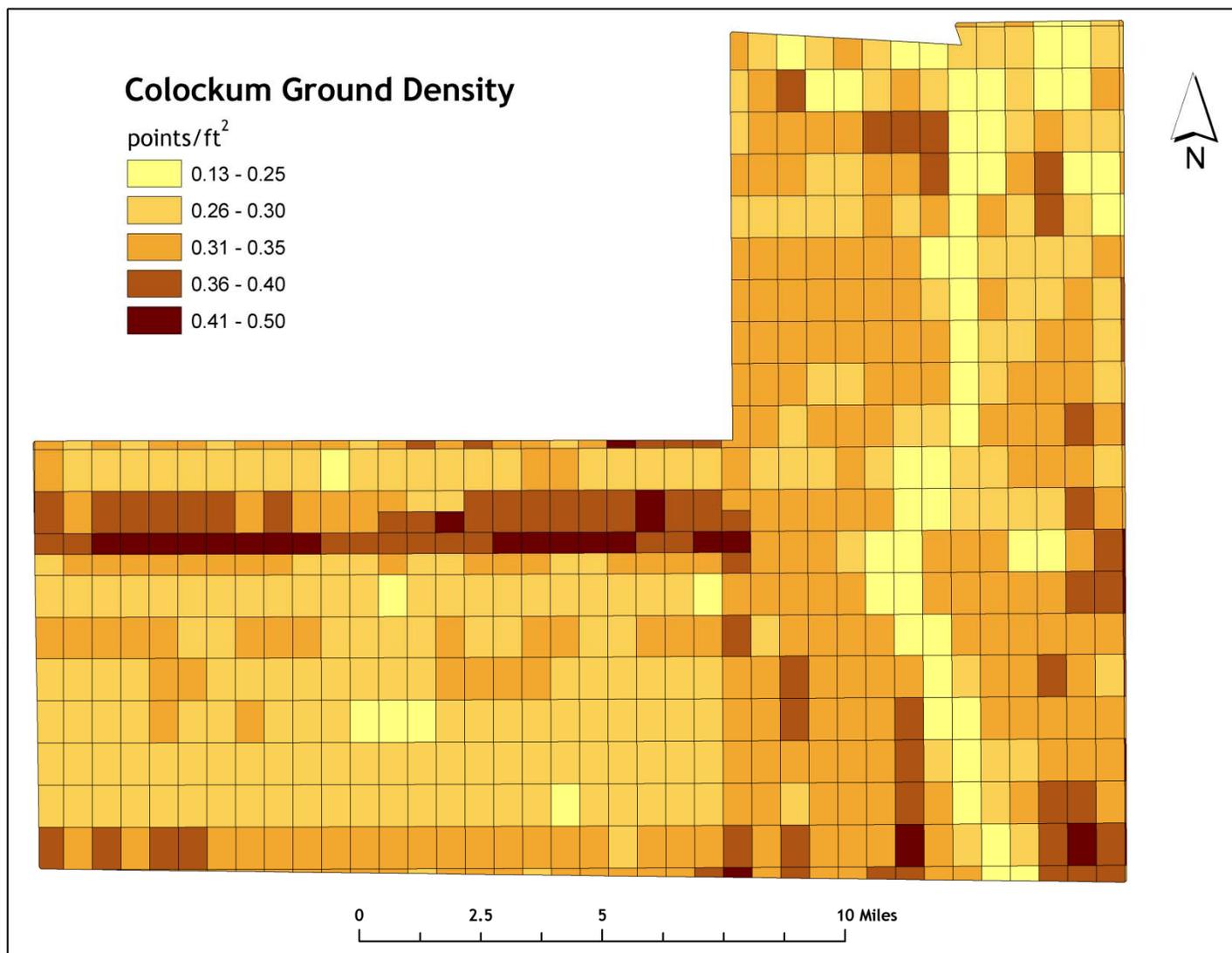
Figure 10. First Return density for the **Rattlesnake** AOI by 1/100th USGS tile.
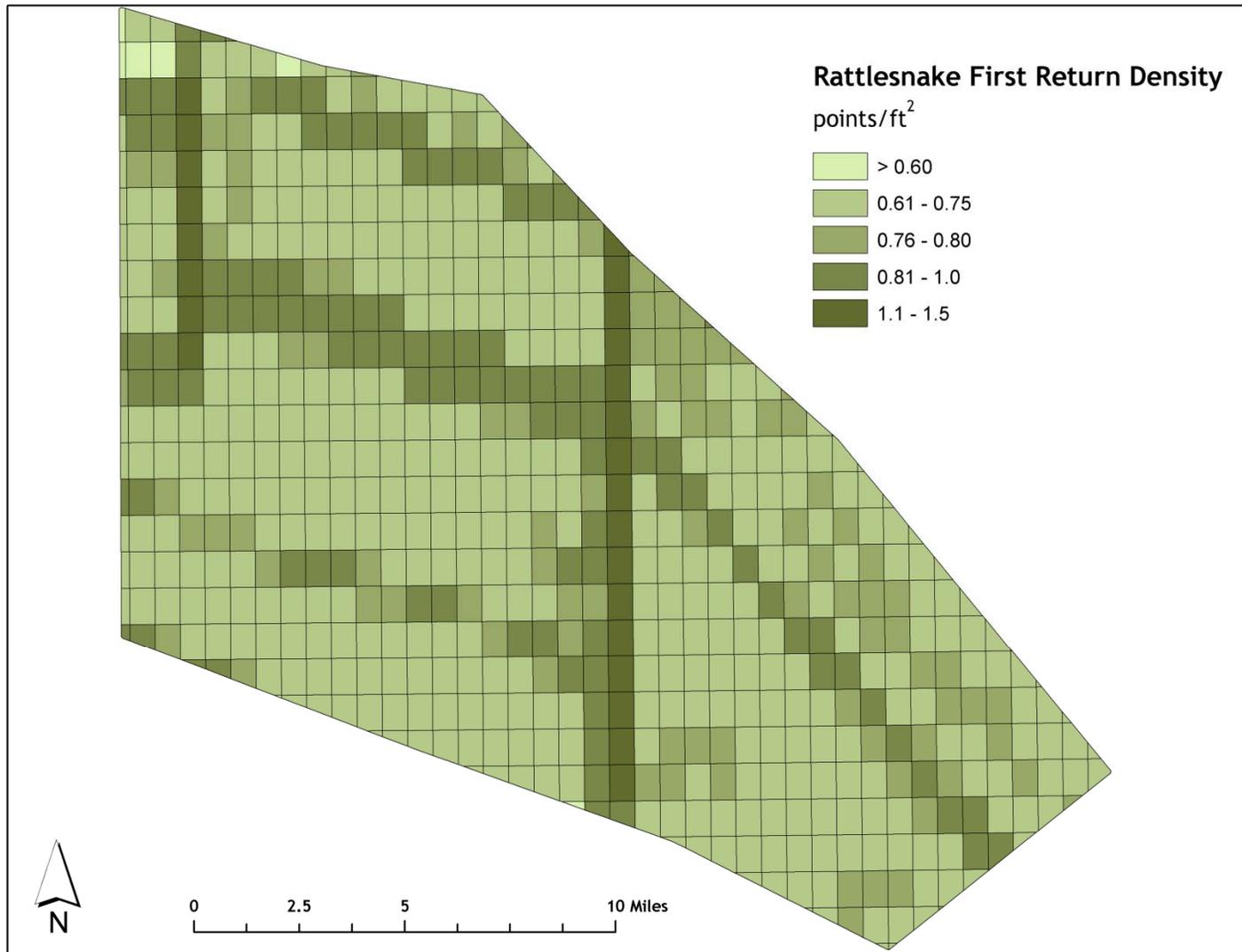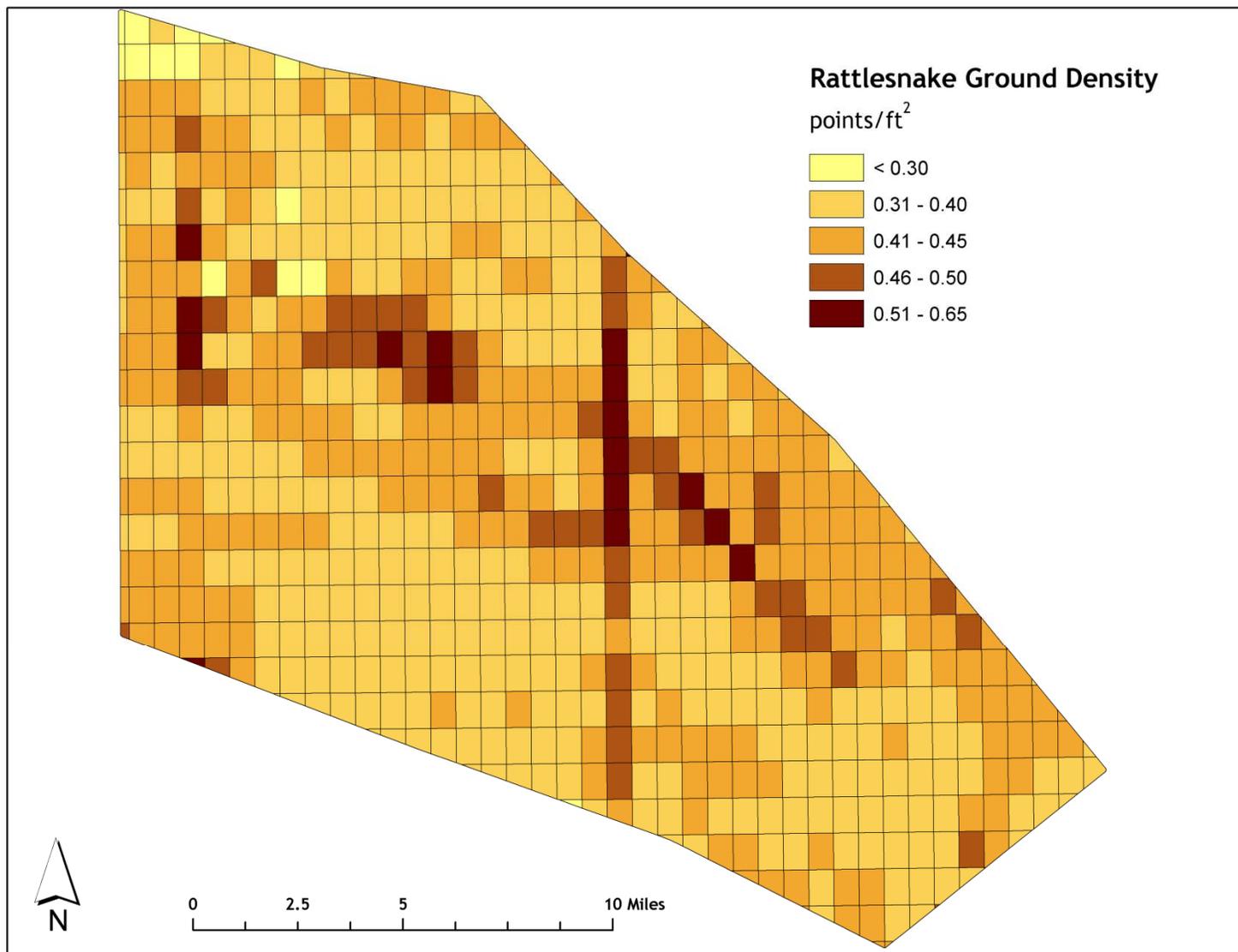
*Figure 11.* *Ground density for the Rattlesnake AOI by 1/100th USGS tile*

5.3 Relative Accuracy Calibration Results

Relative accuracy statistics for the Colockum and Rattlesnake datasets measure the full survey calibration including areas outside the delivered boundary:

Colockum Area of Interest:

- o Project Average = 0.073 ft (0.022 m)
- o Median Relative Accuracy = 0.074 ft (0.023m)
- o 1σ Relative Accuracy = 0.008 ft (0.003 m)
- o 1.96σ Relative Accuracy = 0.016 ft (0.005 m)

Figure 12. Distribution of relative accuracies per flight line, non slope-adjusted.
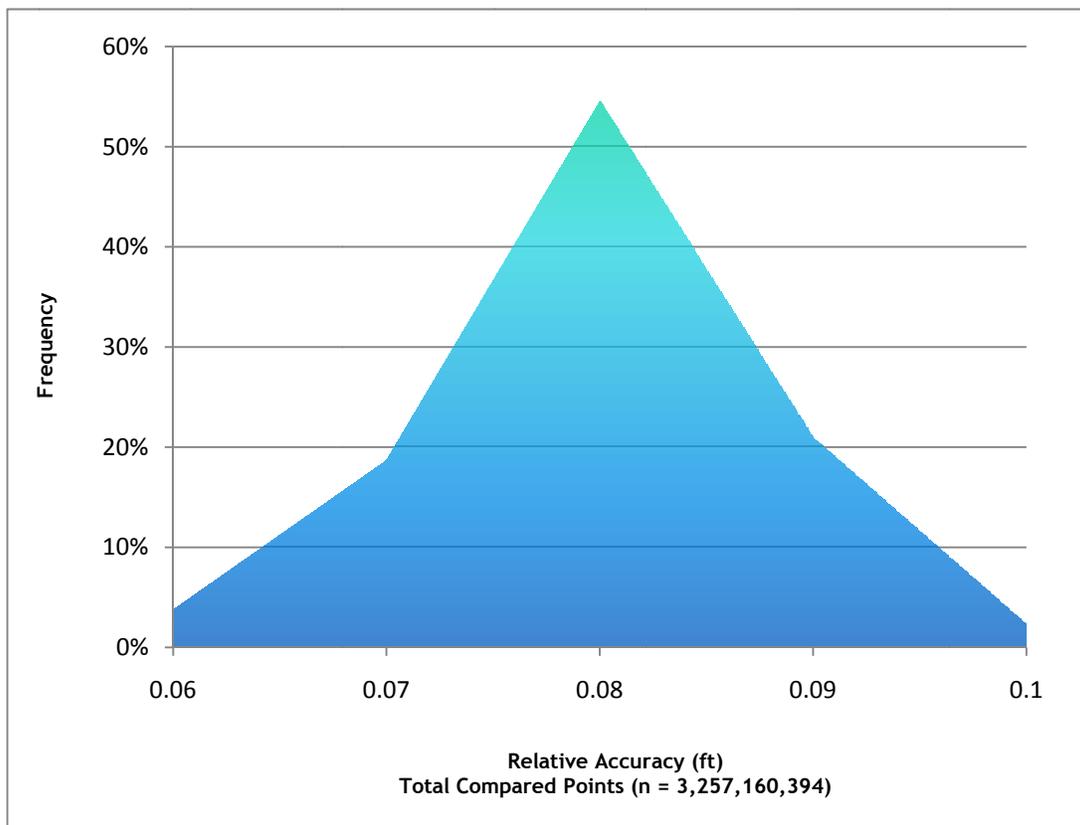
Rattlesnake Area of Interest:

- o Project Average = 0.079 ft (0.024 m)
- o Median Relative Accuracy = 0.077 ft (0.024m)
- o 1σ Relative Accuracy = 0.012 ft (0.004 m)
- o 1.96σ Relative Accuracy = 0.023 ft (0.007 m)

Figure 13. Distribution of relative accuracies per flight line, non slope-adjusted.
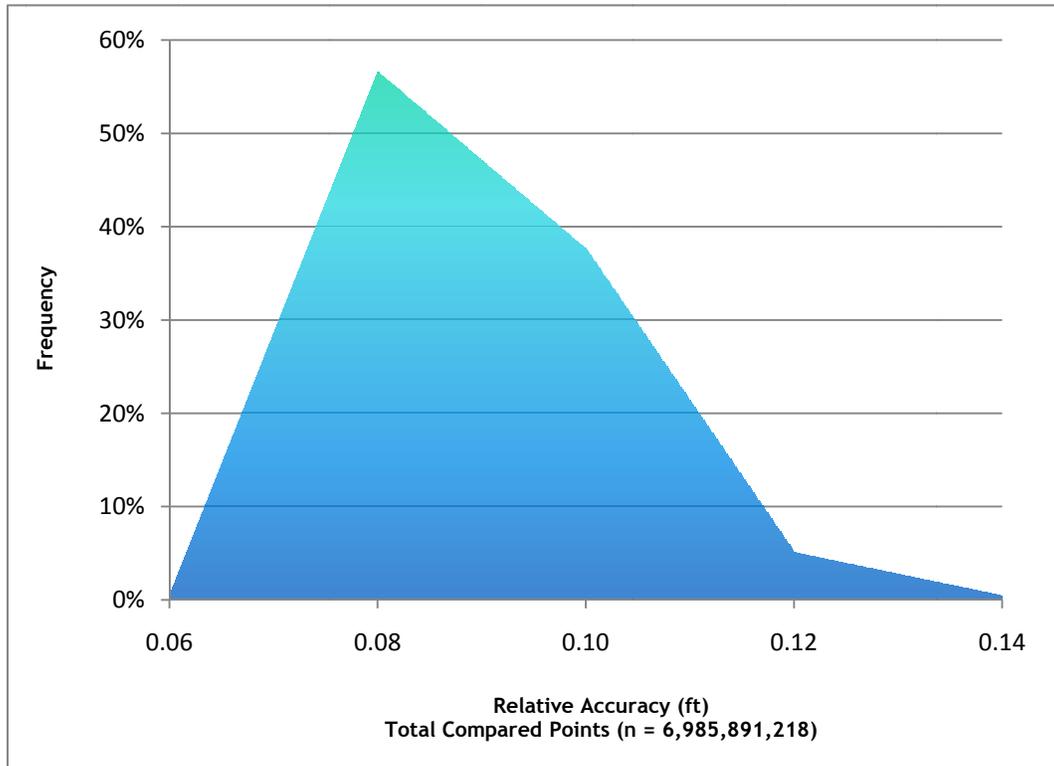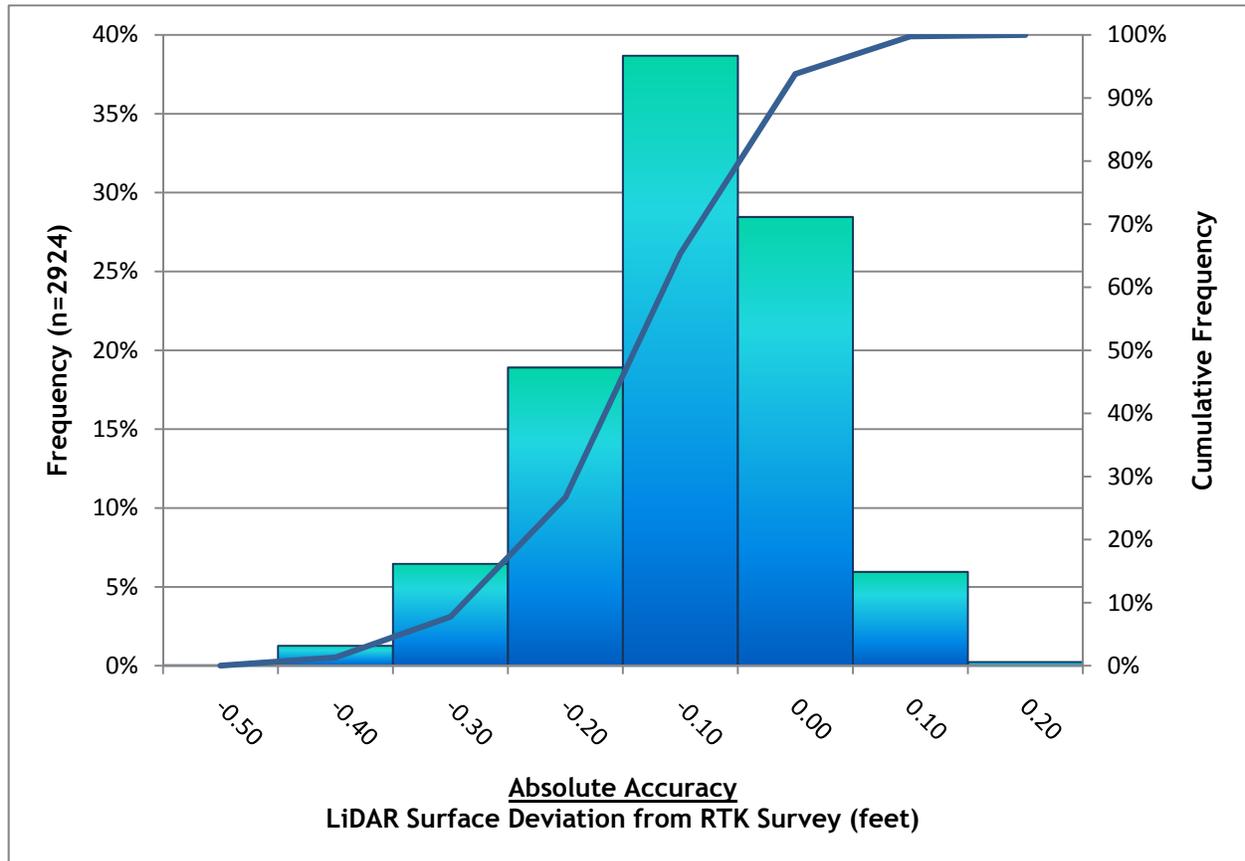
5.4 Absolute Accuracy

Absolute accuracies for the **Colockum** study area:

Table 3. Absolute Accuracy – Deviation between laser points and RTK hard surface survey points.

RTK Survey Sample Size (n): 2924		
Root Mean Square Error (RMSE) = 0.110 ft (0.034 m)		Minimum Δz = -0.420 ft (-0.128 m)
Standard Deviations 1 sigma (σ): 0.101 ft (0.031 m)	1.96 sigma (σ): 0.198 ft (0.060 m)	Maximum Δz = 0.220 ft (0.067 m)
		Average Δz = -0.044 ft (-0.013 m)

*Figure 14. Absolute Accuracy - Histogram Statistics.*

Absolute accuracies for the **Rattlesnake** study area:

Table 4. *Absolute Accuracy – Deviation between laser points and RTK hard surface survey points.*

RTK Survey Sample Size (n): 2064	
Root Mean Square Error (RMSE) = 0.132 ft (0.040 m)	Minimum Δz = -0.476 ft (-0.145 m)
Standard Deviations	Maximum Δz = 0.305 ft (0.093 m)
1 sigma (σ): 0.119 ft (0.036 m) 1.96 sigma (σ): 0.234 ft (0.071 m)	Average Δz = -0.056 ft (-0.017 m)

Figure 15. *Absolute Accuracy - Histogram Statistics.*
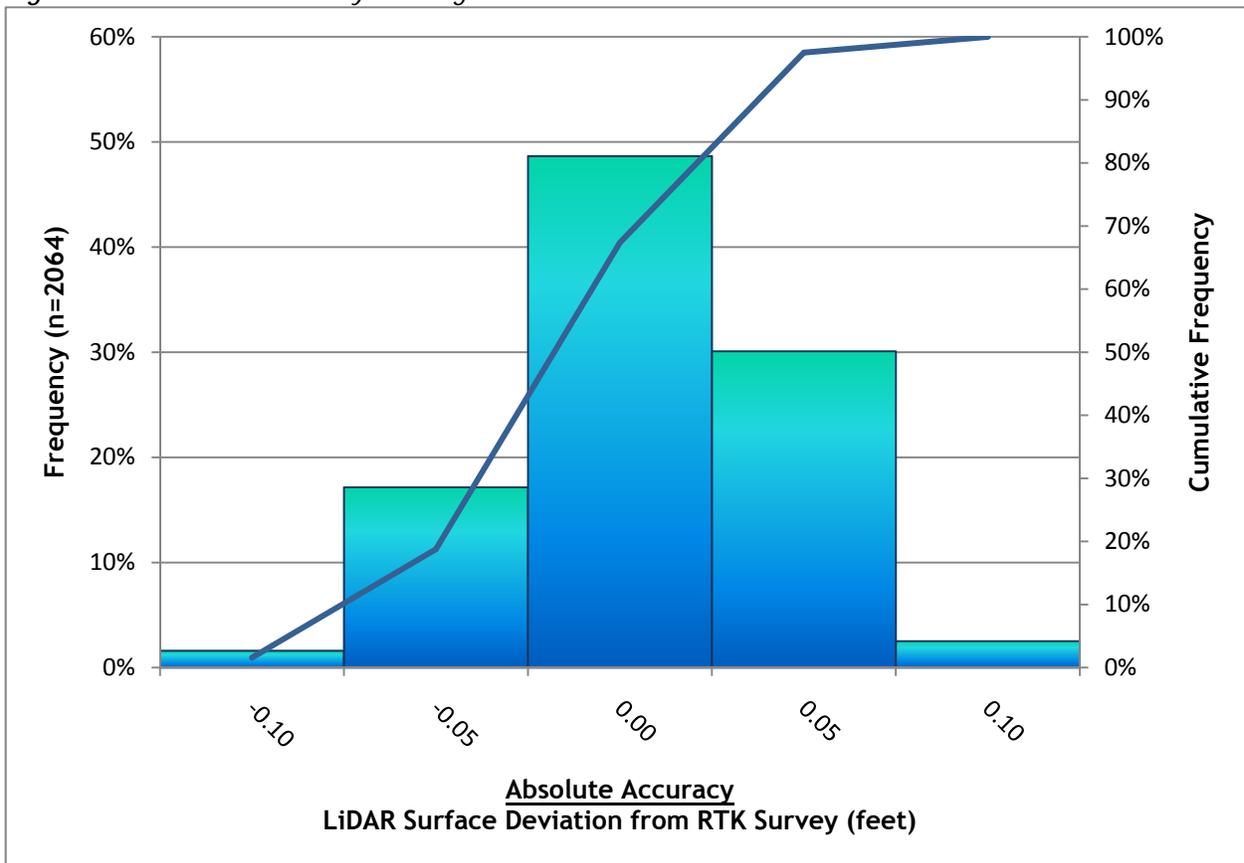
6. Projection/Datum and Units

	Projection:	Washington State Plane South
Datum	**Vertical:**	NAVD88 Geoid03
	Horizontal:	NAD83 (1991 HARN)
	Units:	US Survey Foot

7. Deliverables

Point Data:	LAS 1.2 format (1/100th USGS quad delineation): • All Returns ASCII text format (1/100th USGS quad delineation): • All Returns • Ground points
Vector Data:	• Tile Index for LiDAR Points (Shapefile format) • Tile Index for Rasters (Shapefile format) • Total Area Flown (shapefile format) • SBETs (ASCII textformat)
Raster Data:	• Digital Elevation Models (ESRI GRID format, 3ft resolution, 1/4th USGS quad delineation): • Bare Earth Model • Highest-Hit Model • Intensity Images (GeoTIFF format, 1.5ft resolution, (1/100th USGS quad delineation)
Data Report:	• Full report containing introduction, methodology, and accuracy

Point Data (per 1/100th USGS Quad delineation

- LAS v1.1 or ASCII Format

*Note: Delineation based on 1/100th of a full 7.5-minute USGS Quad (.075-minutes). Larger delineations, such as 1/64th USGS Quads, resulted in unmanageable file sizes due to high data density.

Figure 16. Quadrangle naming convention for 1/100th of a 7.5-minute USGS Quad.

8. Selected Images

Figure 17. View looking south down the Columbia River looking over Sunland near Quincy, WA. Image created from 2009 NAIP Imagery draped over 3D point cloud.
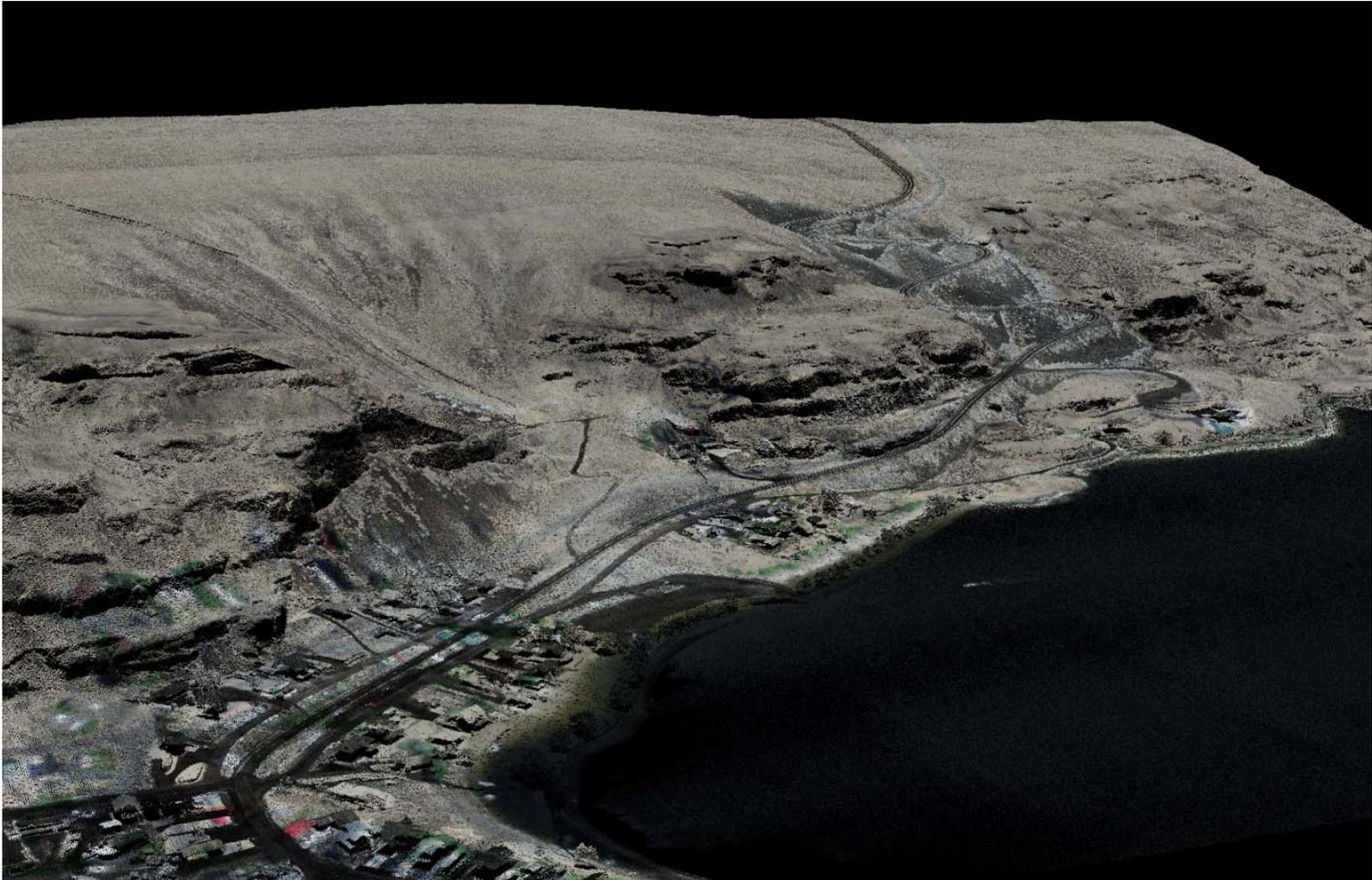
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Figure 18. View looking south down Mansfield Rd to the Columbia River. A passing train is visible in the upper right corner of the image. Image created from 2009 NAIP Imagery draped over 3D point cloud.

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Figure 19. *View looking Northeast at basalt cliffs of the Columbia River Gorge near Crescent Bar Recreational Area. A landslide is visible. Image created from 2009 NAIP Imagery draped over 3D point cloud.*

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Prepared by Watershed Sciences, Inc.

Figure 20. View looking southwest at agricultural fields south of Desert Aire, Washington on the south side of the Columbia River. Image created from 2009 NAIP Imagery draped over 3D point cloud.

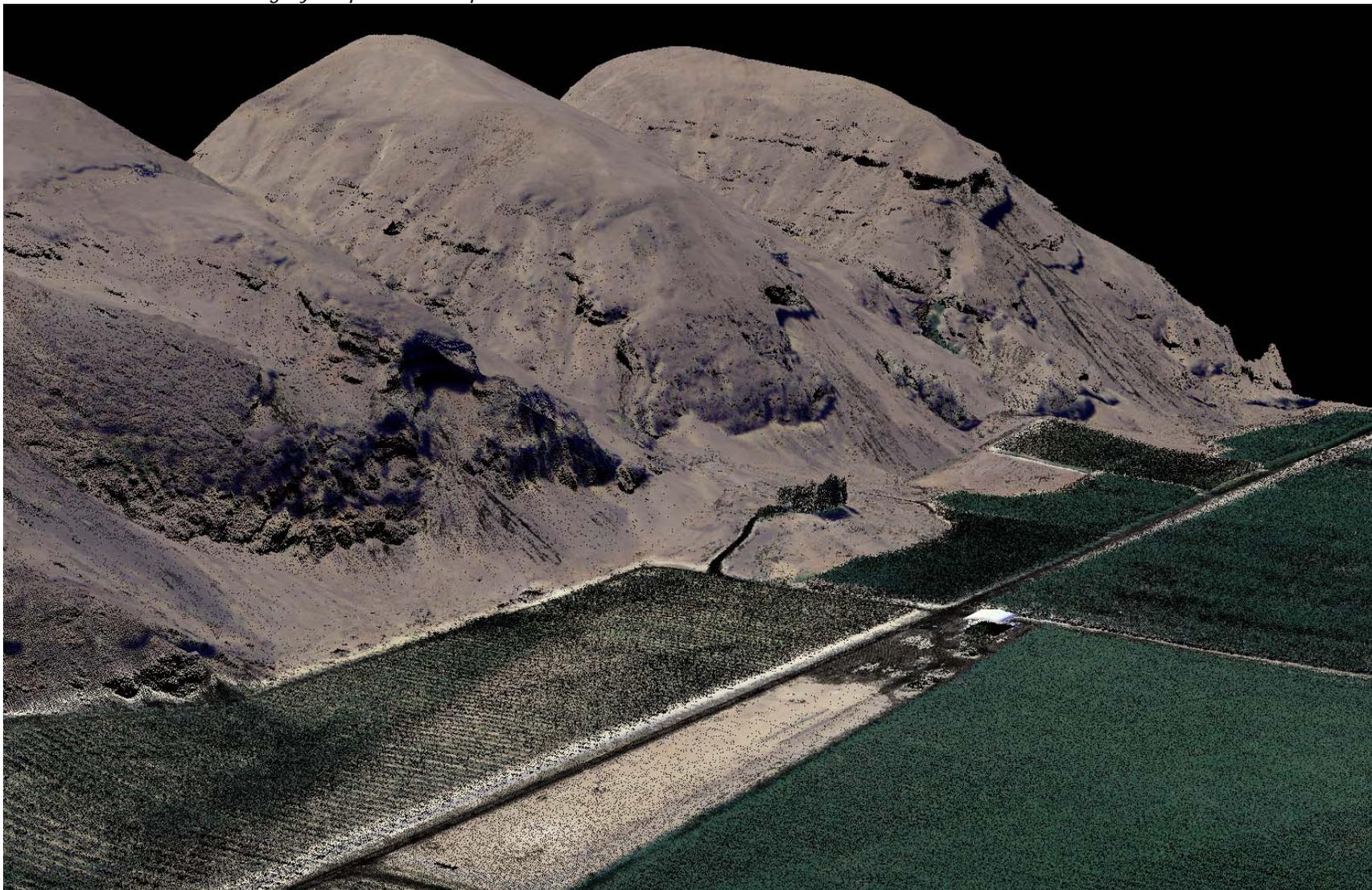**LiDAR Data Acquisition and Processing: Kittitas, WA – Colockum & Rattlesnake Study Areas**

Prepared by Watershed Sciences, Inc.

9. Glossary

1-sigma (σ) Absolute Deviation: Value for which the data are within one standard deviation (approximately 68th percentile) of a normally distributed data set.

1.96-sigma (σ) Absolute Deviation: Value for which the data are within two standard deviations (approximately 95th percentile) of a normally distributed data set.

Root Mean Square Error (RMSE): A statistic used to approximate the difference between real-world points and the LiDAR points. It is calculated by squaring all the values, then taking the average of the squares and taking the square root of the average.

Pulse Rate (PR): The rate at which laser pulses are emitted from the sensor; typically measured as thousands of pulses per second (kHz).

Pulse Returns: For every laser pulse emitted, the Leica ALS 50 Phase II system can record *up to four* wave forms reflected back to the sensor. Portions of the wave form that return earliest are the highest element in multi-tiered surfaces such as vegetation. Portions of the wave form that return last are the lowest element in multi-tiered surfaces.

Accuracy: The statistical comparison between known (surveyed) points and laser points. Typically measured as the standard deviation (sigma, σ) and root mean square error (RMSE).

Intensity Values: The peak power ratio of the laser return to the emitted laser. It is a function of surface reflectivity.

Data Density: A common measure of LiDAR resolution, measured as points per square meter.

Spot Spacing: Also a measure of LiDAR resolution, measured as the average distance between laser points.

Nadir: A single point or locus of points on the surface of the earth directly below a sensor as it progresses along its flight line.

Scan Angle: The angle from nadir to the edge of the scan, measured in degrees. Laser point accuracy typically decreases as scan angles increase.

Overlap: The area shared between flight lines, typically measured in percents; 100% overlap is essential to ensure complete coverage and reduce laser shadows.

DTM / DEM: These often-interchanged terms refer to models made from laser points. The digital elevation model (DEM) refers to all surfaces, including bare ground and vegetation, while the digital terrain model (DTM) refers only to those points classified as ground.

Real-Time Kinematic (RTK) Survey: GPS surveying is conducted with a GPS base station deployed over a known monument with a radio connection to a GPS rover. Both the base station and rover receive differential GPS data and the baseline correction is solved between the two. This type of ground survey is accurate to 1.5 cm or less.

10. Citations

Soininen, A. 2004. TerraScan User's Guide. TerraSolid.

Appendix A

LiDAR accuracy error sources and solutions:

Type of Error	Source	Post Processing Solution
GPS (Static/Kinematic)	Long Base Lines	None
	Poor Satellite Constellation	None
	Poor Antenna Visibility	Reduce Visibility Mask
Relative Accuracy	Poor System Calibration	Recalibrate IMU and sensor offsets/settings
	Inaccurate System	None
Laser Noise	Poor Laser Timing	None
	Poor Laser Reception	None
	Poor Laser Power	None
	Irregular Laser Shape	None

Operational measures taken to improve relative accuracy:
1. <u>Low Flight Altitude</u>: Terrain following is employed to maintain a constant above ground level (AGL). Laser horizontal errors are a function of flight altitude above ground (i.e., ~ 1/3000th AGL flight altitude).
2. <u>Focus Laser Power at narrow beam footprint</u>: A laser return must be received by the system above a power threshold to accurately record a measurement. The strength of the laser return is a function of laser emission power, laser footprint, flight altitude and the reflectivity of the target. While surface reflectivity cannot be controlled, laser power can be increased and low flight altitudes can be maintained.
3. <u>Reduced Scan Angle</u>: Edge-of-scan data can become inaccurate. The scan angle was reduced to a maximum of ±15° from nadir, creating a narrow swath width and greatly reducing laser shadows from trees and buildings.
4. <u>Quality GPS</u>: Flights took place during optimal GPS conditions (e.g., 6 or more satellites and PDOP [Position Dilution of Precision] less than 3.0). Before each flight, the PDOP was determined for the survey day. During all flight times, a dual frequency DGPS base station recording at 1–second epochs was utilized and a maximum baseline length between the aircraft and the control points was less than 19 km (11.5 miles) at all times.
5. <u>Ground Survey</u>: Ground survey point accuracy (i.e. <1.5 cm RMSE) occurs during optimal PDOP ranges and targets a minimal baseline distance of 4 miles between GPS rover and base. Robust statistics are, in part, a function of sample size (n) and distribution. Ground survey RTK points are distributed to the extent possible throughout multiple flight lines and across the survey area.
6. <u>50% Side-Lap (100% Overlap)</u>: Overlapping areas are optimized for relative accuracy testing. Laser shadowing is minimized to help increase target acquisition from multiple scan angles. Ideally, with a 50% side-lap, the most nadir portion of one flight line coincides with the edge (least nadir) portion of overlapping flight lines. A minimum of 50% side-lap with terrain-followed acquisition prevents data gaps.
7. <u>Opposing Flight Lines</u>: All overlapping flight lines are opposing. Pitch, roll and heading errors are amplified by a factor of two relative to the adjacent flight line(s), making misalignments easier to detect and resolve.