

METADATA FOR NASA GODDARD'S LIDAR, HYPERSPECTRAL AND THERMAL (G-LiHT) AIRBORNE IMAGER

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1) CONTACT INFORMATION

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2) CAMPAIGN INFORMATION

Date(s): June 2014
Time of day: see ancillary file for acquisition time
Location: Rochester, NH
Description: Mapping of semi-urban forests with signs of insect damage
Research project: Forest Health
Funding source: USFS Durham Field Office

3) FLIGHT PLANS

Large mapping areas with 30% overlap of high interest semi-urban areas with history of insect damage.

4) ACQUISITION DETAILS

Aircraft: USFS C206
Pilot: Mary Very, USFS
G-LiHT operator(s): Larry Corp NASA GSFC
Nominal altitude (AGL): 335 m AGL
Nominal velocity: 110-130 kt
Other:

5) FIELD OBSERVATIONS

Weather: variable
Other notes: VFR

6) OUTPUT FILE NAME(S)

Andover_Jun2014
Bend_OR_May2014
Bow_Jun2014
Dublin_Jun2014
Hanover_Jun2014
Keen_Jun2014
Loudon_Jun2014
Nashua_Jun2014
New_Hampton_Jun2014
Newburyport_Jun2014
Northwood_Jun2014

7) DATA PRODUCTS

GPS-INS

Trajectory: Aircraft location and orientation (roll, pitch, yaw). Available as 3D Google Earth overlay (KML) and 250 Hz data product (ASCII).

LiDAR

Canopy Height Model: Lidar-derived maximum canopy height (m AGL) and canopy rugosity (i.e., standard deviation of heights within an area equivalent to a 1/24 ac USFS-FIA subplot).

Available as Google Earth overlay (KML) and raster data product (GeoTIFF) at a nominal 1 m spatial resolution.

Digital Terrain Model: Lidar-derived bare earth elevation (m, EGM96 geoid), aspect and slope. Available as Google Earth overlay (KML) and raster data product (GeoTIFF) at a nominal 1 m spatial resolution.

Lidar Apparent Reflectance: Mean reflectance for all, single returns from a 1550 nm laser. The lidar is factory calibrated and data corrected for ranging distance, but not scan angle or atmospheric interactions. Available as raster data product (GeoTIFF) at a nominal 1 m spatial resolution.

Lidar Point Cloud: Individual lidar return data, including 3D coordinates; classified ground returns ("Classification" field); AGL heights ("Point Source ID Text" field, using z scale factor and offsets); and lidar apparent reflectance ("Intensity" field; -25 to 0 dB for 2 byte range). Overlapping swaths are co-aligned with coincident ground returns to remove swath-to-swath elevation biases. Available in ASPRS LAS 1.1 format.

Lidar Metrics: Common lidar height, density, fractional cover and return statistics (e.g., mean pulse density, returns per pulse) for all returns +/- 15 degrees of nadir. Available as raster data product (GeoTIFF) at a nominal 13 m spatial resolution (area equivalent to a 1/24 ac USFS-FIA subplot).

Image Spectrometer

All VNIR (418 to 918 nm, 4.5 nm sampling interval) data products are available as orthorectified raster files (ENVI file format) at a nominal 1 m spatial resolution; Google Earth overlays (KML) are available for the NIR band.

Radiance: Calibrated radiance data is provided for individual swaths in radiometric units ($W m^{-2} sr^{-1} nm^{-1}$).

At-sensor reflectance: Computed as the ratio between observed upwelling radiance and downwelling hemispheric irradiance; corrected for differences in cross-track illumination and BRDF using an empirically derived multiplier. At a nominal flying height of 335 m AGL, the at-sensor reflectance is a close approximation of surface reflectance. Available for individual swaths, and mosaicked for mapped areas using swath observations closest to nadir.

Vegetation indices: Computed from at-sensor reflectance data. These products are used as indicators of canopy properties and condition (e.g., greenness, pigment concentrations).

Ancillary data: Contains acquisition time, aircraft location, sun-sensor geometry, incoming PAR, clearness index, swath ID, and flag indicating nearest neighbor resampling during georegistration.

Thermal

Radiant temperature: Computed with 0.98 emissivity and no atmospheric or view angle correction. Available as Google Earth overlay (KML) and raster data product (GeoTIFF) at a nominal 1 m spatial resolution.

8) INSTRUMENT SPECIFICATIONS

GPS-INS

Model/Make: RT-4041, GPS and GLONAS enabled; Oxford Technical Solutions, Oxfordshire, UK

Serial number: 663

Sampling interval: 250 Hz

Differential correction: OmniStar HP or G2

Positional accuracy (1 sigma): 10 to 15 cm horizontal (vertical=horizontal*1.5)

Yaw accuracy (1 sigma): 0.1 degree

Roll accuracy (1 sigma): 0.03 degree

Pitch accuracy (1 sigma): 0.03 degree

Antenna: Antcom G5Ant-42AT1 L1/L2 Glonas/GPS/OmniStar

Post-Processing software: RT Post-Process

Scanning lidar

Model/Make: VQ-480; Riegl Laser Measurement Systems, Horn, Austria

Serial number: S9997785

Laser wavelength: 1550 nm

Pulse width: 3 ns

Pulse energy: 2817 nJ in 25 mm

Beam divergence: 0.3 mrad
Nominal footprint size: $\text{diameter} = \tan(\text{beam divergence}/2) * \text{altitude} * 2$
Laser pulse repetition frequency (PRF): 300 kHz
Effective measurement frequency: $0.5 * \text{PRF}$
Maximum number of returns per pulse: 8
Field of view: 60 degrees (+/- 30 degrees of nadir)
Scan mode: line
Scan rate: 100 lines per second
Nominal distance between points in a scan line: 0.24 m
Nominal distance between scan lines: 0.56 m
Swath size: $\text{width} = \tan(\text{FOV}/2) * \text{altitude} * 2$
Lever arm (ahead, left, above; date): 1.380, 1.1440, 1.105 m (22 May 2014)
Boresight (roll, pitch, yaw; date): -0.03381, -0.06280, -0.59620 degrees (22 May 2014)
Post-Processing software: RiProcess

Profiling lidar: none

Digital SLR:

Camera: Nikon D7100
Lens: 20mm f/2.8D lens w/circular polarizer
FOV: 60.7×42.6 degree
Image area and size: DX, $6000 \times 4000 = 24$ megapixel
Shutter speed: $1/250$ s, EV -1.3
Aperture: f/2.8
ISO: 100
Focus: manual, infinity
White balance: sunlight
Frame rate: 4 s
Image format: jpg
Quantization: 8-bit

Imaging spectrometer

Model/Make: Hyperspec model 1002A-00451; Headwall Photonics, Fitchburg, MA
Serial Number: G4-105
Camera: Adimec model RA1000m/D_DFG
Serial Number: 830016
Focal plane array: pushbroom, 1004 cross track pixels
Frame rate: 50 Hz
Lens/FOV: 8 mm lens, f/2; ~50 degree
Sensor size: 7.4 mm
Integration time: 20 msec
Sensor range: 417-1008 nm
Spectral band width (FWHM): ~8 to 15 nm
Sampling resolution: 1.5 nm (401 bands)
Resampled resolution: 418 to 919 nm in 4.5 nm bands (114 bands)
Quantization: 12 bit

Thermal camera

Model/Make: Gobi-384; Xenics, Leuven, Belgium
Serial number: GOBI-1413
Sensor: Uncooled microbolometer
Focal plane array: 384×288 on 25 um pixels
Data output: degrees Celsius
Frame rate: 25 Hz
Sensitivity: 8 to 14 um
Quantization: 16 bit

Downwelling irradiance

Model/Make: USB-4000; Ocean Optics, Dunedin, FL
Serial number: USB4H02819
FOV: 180 degrees (cosine diffusor)
Integration time: 33 ms
Sample averaging: 30
Sampling interval: 0.6 nm
Sensor range: 380-1100 nm
FWHM: 1.5 nm
Resampled resolution: 418 to 919 nm in 4.5 nm bands (114 bands)

Quantization: 16 bit

9) PUBLICATIONS

Cook, B. D., L. W. Corp, R. F. Nelson, E. M. Middleton, D. C. Morton, J. T. McCorke1, J. G. Masek, K. J. Ranson, and V. Ly. 2013. NASA Goddard's Lidar, Hyperspectral and Thermal (G-LiHT) airborne imager. Remote Sensing 5:4045-4066, doi:10.3390/rs5084045.