Data Collection and processing report for the Seed project:

"Exhumation of precariously balanced rocks in the Mojave Desert: refining methods of seismic hazard analysis."

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1. LiDAR System Description and Specifications

This survey was performed with an Optech Gemini Airborne Laser Terrain Mapper (ALTM) serial number 06SEN/CON195 mounted in a twin-engine Cessna 337 Skymaster aircraft (Tail Number 337P). The instrument nominal specifications are listed in table 1.

Operating Altitude	150-4000 m, Nominal
Horizontal Accuracy	1/5,500 x altitude (m AGL); 1 sigma
Elevation Accuracy	5 - 35 cm; 1 sigma
Range Capture	Up to 4 range measurements, including 1st, 2nd, 3rd, last returns
Intensity Capture	12-bit dynamic range for all recorded returns, including last returns
Scan FOV	0 - 50 degrees; Programmable in increments of ±1degree
Scan Frequency	0 – 70 Hz
Scanner Product	Up to Scan angle x Scan frequency = 1000
Roll Compensation	±5 degrees at full FOV – more under reduced FOV
Pulse Rate Frequency	33 - 167 kHz
Position Orientation System	Applanix POS/AV 510 OEM includes embedded BD960 72-channel 10Hz (GPS and Glonass) receiver
Laser Wavelength/Class	1054 nanometers / Class IV (FDA 21 CFR)
Beam Divergence nominal (full angle)	Dual Divergence 0.25 mrad (1/e) or 0.80 mrad (1/e)

Table 1 – Optech GEMINI specifications (http://www.optech.ca/gemini.htm).

See http://www.optech.ca for more information from the manufacturer.

2. Area of Interest.

The survey area is defined by a rectangular polygon located along Interstate 40 between Daggett and Needles in the Mojave Desert of California (some 110 km east of Daggett). The polygon dimensions are 3.85 x 6.54 km, with a surface area of 25.0 km². The location and extent of the polygon are shown below in Figure 1.
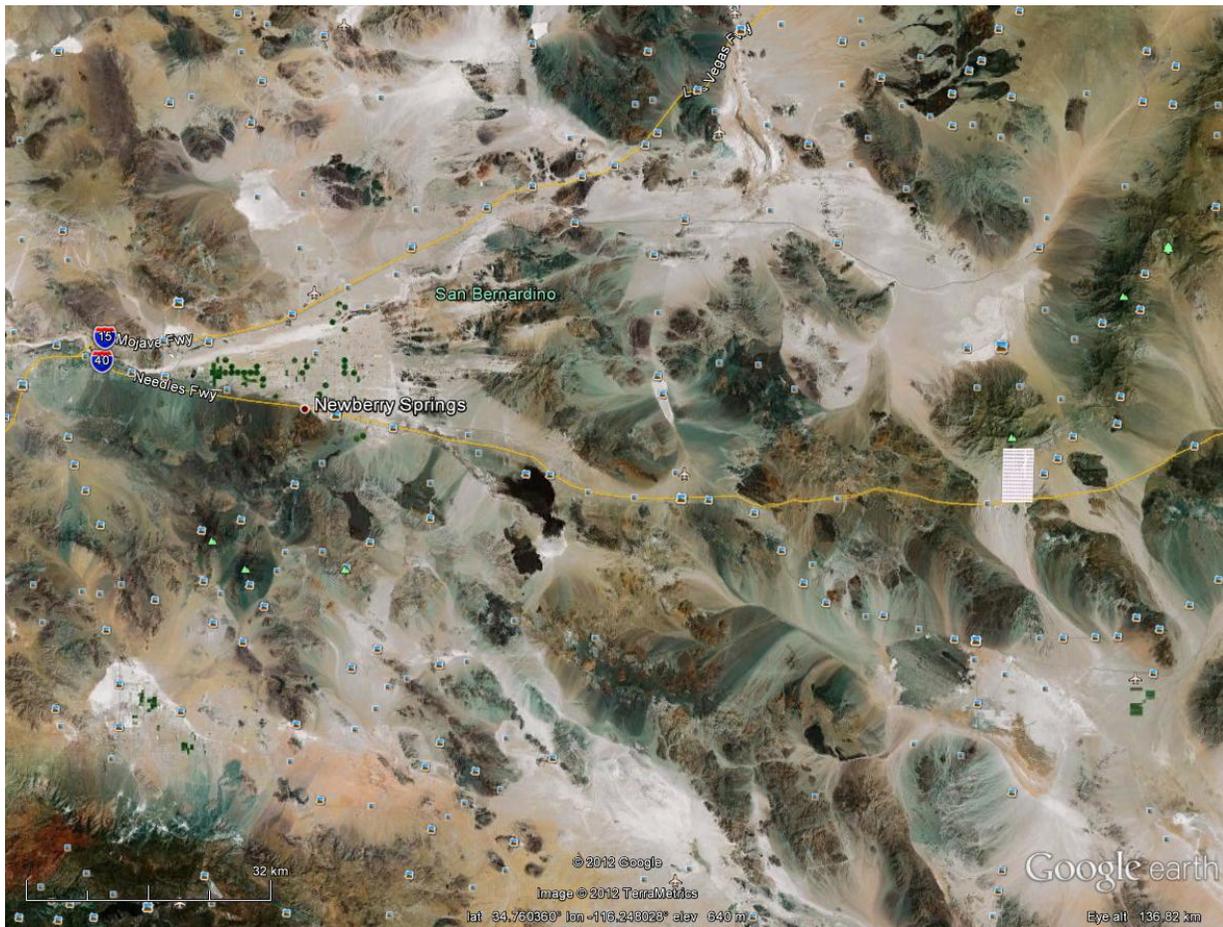

Figure 1 – Shape and location of survey polygon (Google Earth).

3. Data Collection

a)   **Survey Dates**: The survey took place on March 14, 2012 (DOY 074) following plan file: Harvey_CA_Mojave_V1m.pln. The plan consisted of 39 project lines running east to west as depicted on Figure 2. Two additional lines, also shown on Figure 2, one perpendicular to the project lines and one oblique were added to the plan to perform system and data calibration. The Barstow-Daggett Airport (KDAG) was used as base for this mission.

Figure 2 – Shape and location of survey polygon (Google Earth).

**b) Airborne Survey Parameters:** The survey parameters are provided in Table 2 below

Nominal Flight Parameters		Equipment Settings		Survey Totals	
Flight Altitude	600m AGL	Laser PRF	100 kHz	Total Flight Time	3.64 hrs
Flight Speed	60 m/s	Beam Divergence	0.25 mrad	Total Laser Time	0.93 hrs
Swath Width	360 m	Scan Frequency	48 Hz	Total Swath Area	26.99 km^2
Swath Overlap	50%	Scan Angle	± 19°	Total AOI Area	25 km^2
Point Density	8.08 p/m²	Scan Cutoff	2°		

Table2 – Survey Parameters and Totals.

c) Ground GPS: Three GPS reference station locations were used during the survey, the stations are part of the UNAVCO PBO GPS network, see http://pbo.unavco.org/data/gps. Observations were logged at 1 Hz. Table 3 gives the coordinates of the stations, and Figure 3 shows the location of the GPS stations with respect to the project area.

GPS station	GMRC	I40A	P603
Operating agency	UNAVCO	UNAVCO	UNAVCO
Latitude	34.78399	34.72732	34.71690
Longitude	-115.66022	-115.91144	-116.02949
Ellipsoid Height (m)	1298.972	766.066	625.457

Table 3 – GPS Coordinates of ground reference stations
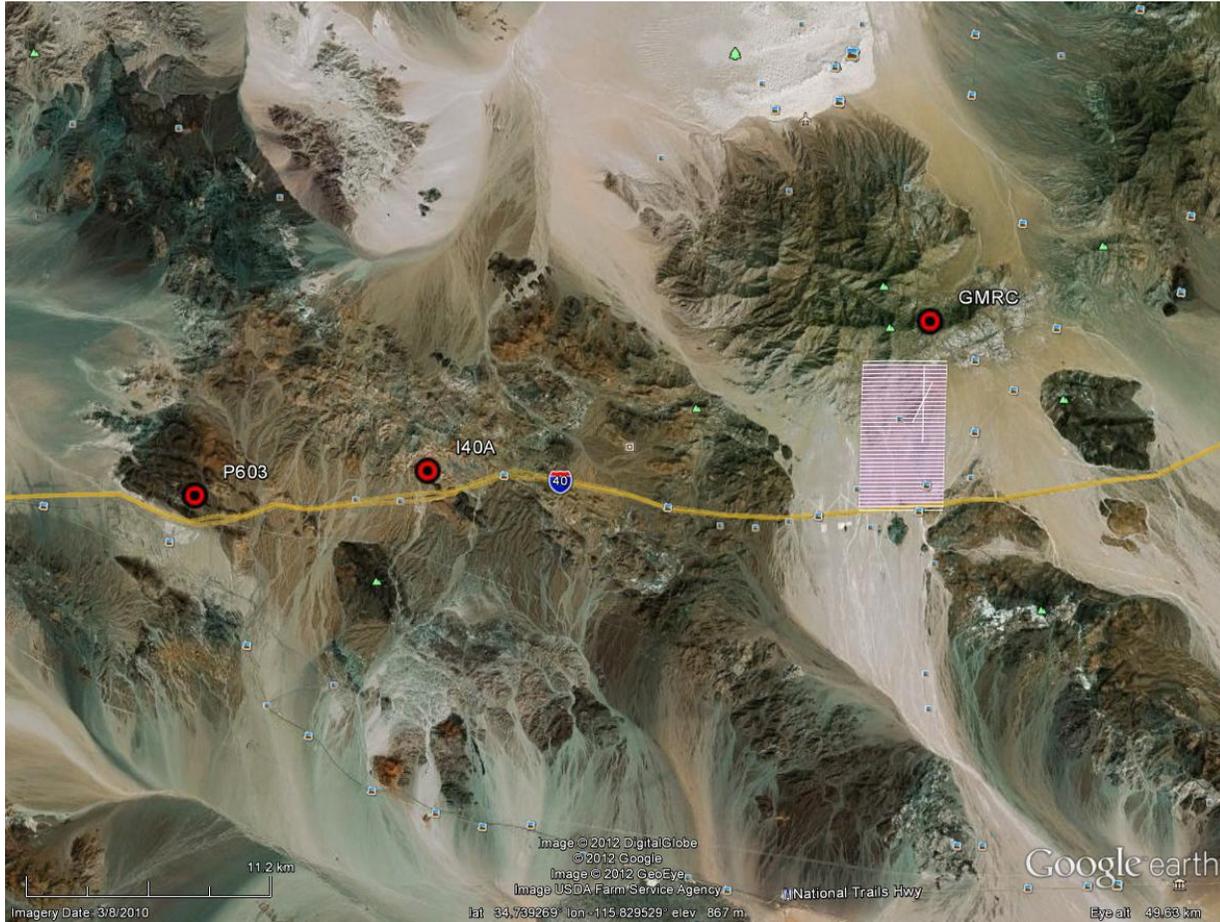
Figure 3 – Location of the GPS Stations used in the survey (Google Earth).

4. GPS/IMU Data Processing

Reference coordinates for all NCALM stations are derived from observation sessions taken over the project duration and submitted to the NGS on-line processor OPUS which processes static differential baselines tied to the international CORS network. For further information on OPUS see http://www.ngs.noaa.gov/OPUS/ and for more information on the CORS network see http://www.ngs.noaa.gov/CORS/

Airplane trajectories for this survey were processed using KARS (Kinematic and Rapid Static) software written by Dr. Gerald Mader of the NGS Research Laboratory. KARS kinematic GPS

processing uses the dual-frequency phase history files of the reference and airborne receivers to determine a high-accuracy fixed integer ionosphere-free differential solution at 1 Hz. All final aircraft trajectories for this project are blended solutions from the three stations.

After GPS processing, the trajectory solution and the raw inertial measurement unit (IMU) data collected during the flights are combined in APPLANIX software POSPac MMS (Mobile Mapping Suite Version 5.2). POSPac MMS implements a Kalman Filter algorithm to produce a final, smoothed, and complete navigation solution including both aircraft position and orientation at 200 Hz. This final navigation solution is known as an SBET (Smoothed Best Estimated Trajectory).

5. LiDAR Data Processing Overview

The following diagram (Figure 4) shows a general overview of the NCALM LiDAR data processing workflow
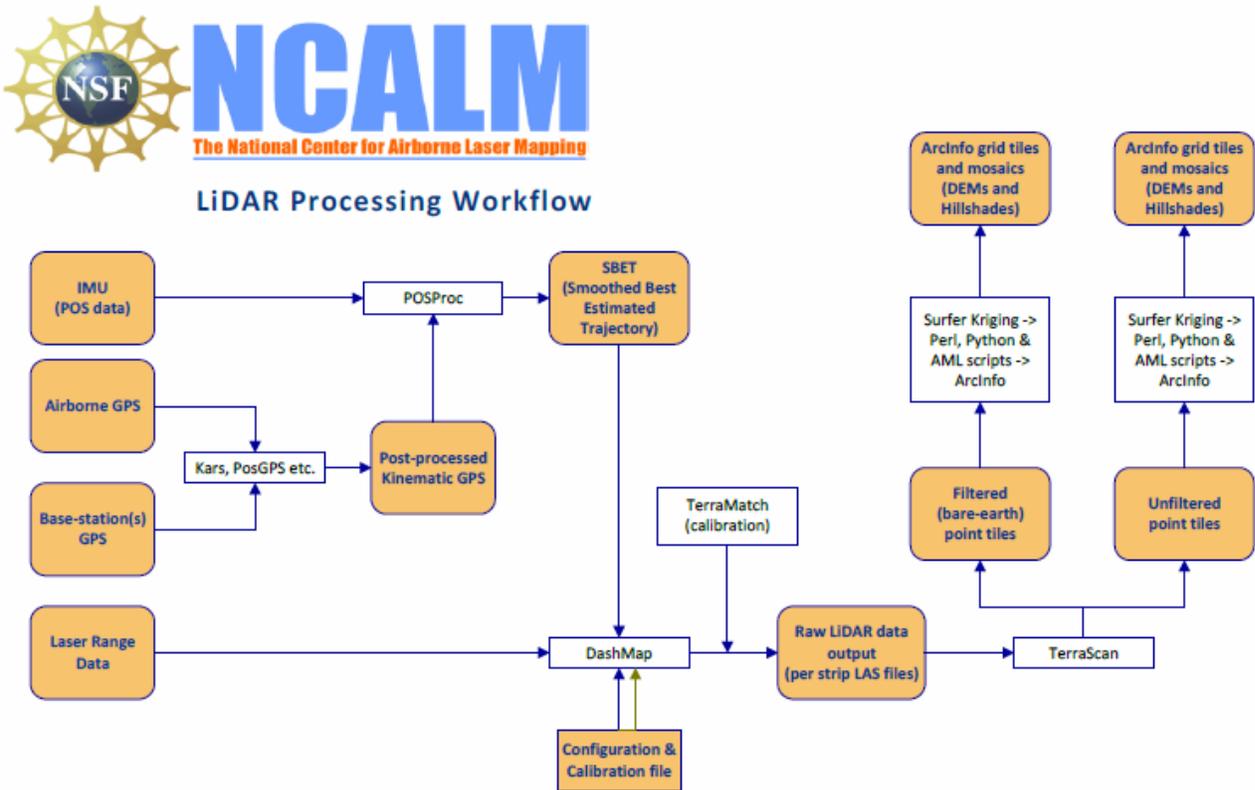
Figure 4 NCALM LiDAR Processing Workflow

NCALM makes every effort to produce the highest quality LiDAR data possible but every LiDAR point cloud and derived DEM will have visible artifacts if it is examined at a sufficiently fine level. Examples of such artifacts include visible swath edges, corduroy (visible scan lines), and data gaps.

A detailed discussion on the causes of data artifacts and how to recognize them can be found here:

http://ncalm.berkeley.edu/reports/GEM_Rep_2005_01_002.pdf .

A discussion of the procedures NCALM uses to ensure data quality can be found here:

NCALM cannot devote the required time to remove all artifacts from data sets, but if researchers find areas with artifacts that impact their applications they should contact NCALM and we will assist them in removing the artifacts to the extent possible – but this may well involve the PIs devoting additional time and resources to this process.

Classification done by automated means using TerraSolid Software – removal of outliers only.
http://www.terrasolid.fi/en/products/4

6. Data Deliverables

a) **Horizontal Datum**: NAD83(2011)
b) **Vertical Datum:** GEOID 09
c) **Projection:** UTM Zone 11N
d) **File Formats:**

1. Point Cloud in LAS format, unclassified per PI request, in 1 km square tiles.
2. ESRI format 1-m DEM from default-class points.
3. ESRI format 1-m Hillshade raster from default-classd points

e) **File naming convention:** 1 Km tiles follow a naming convention using the lower left coordinate (minimum X, Y) as the seed for the file name as follows: XXXXXX_YYYYYY. For example if the tile bounds coordinate values from easting equals 619000 through 620000, and northing equals 3848000 through 3849000 then the tile filename incorporates 619000_3848000. These tile footprints are available as an AutoCAD DXF or ESRI shapefile. The ESRI DEMs are single mosaic files created by combining together the 1KM tiles. Their name consists of prefix 'ume' (indicating that the DEM is made using default-class points) and the lowest Easting coordinate rounded to the nearest 1000, for e.g. 'ume617000'. The hillshade files have a prefix 'sh' after the name, for e.g. 'ume617000sh'.

7. Notes

Ground classification was NOT performed on these data per PI request. The project area had sparse vegetation and extremely steep cliffs and canyons.