

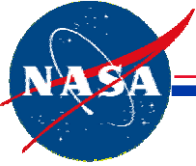
SSC Geopositional Assessment of the Advanced Wide Field Sensor

Kenton Ross

Science Systems and Applications, Inc.
John C. Stennis Space Center, MS 39529
228-688-1869

Kenton.Ross@ssc.nasa.gov

USDA FAS/PECAD Seminar
ResourceSat – AWiFS and LISS Data
Fairfax, Virginia, USA
September 12, 2006



Contributors

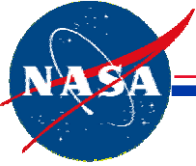
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NASA: Thomas Stanley

Science Systems & Applications, Inc.: Mary Pagnutti

Computer Sciences Corporation: Debbie Fendley

Participation in this work by Science Systems and Applications, Inc., and by Computer Sciences Corporation was supported by NASA at the John C. Stennis Space Center, Mississippi, under Task Order NNS04AB54T.



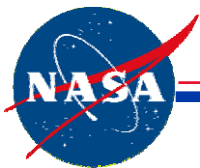
2005 Overview

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- **OBJECTIVE:** Provide independent verification of IRS geopositional accuracy claims and of the internal geopositional characterization provided by Lutes (2005)¹
- Assessed six sub-scenes (Quads): three from each AWiFS camera
- Manually matched check points to digital orthophoto quarter quadrangle (DOQQ) reference (assumed accuracy ~5 m, RMSE)
- Check points were selected to meet or exceed Federal Geographic Data Committee's guidelines²
- Used ESRI ArcGIS® for data collection and SSC-written MATLAB® scripts for data analysis

¹ Lutes, J., 2005. Resourcesat-1 geometric accuracy assessment. In proceedings of The ASPRS 2005 Annual Conference, Baltimore, MD, March 7–11. Available at http://www.spaceimaging.com/whitepapers_pdfs/2005/Lutes_ASPRS2005_ResourceSat_Accuracy_Assessment.pdf.

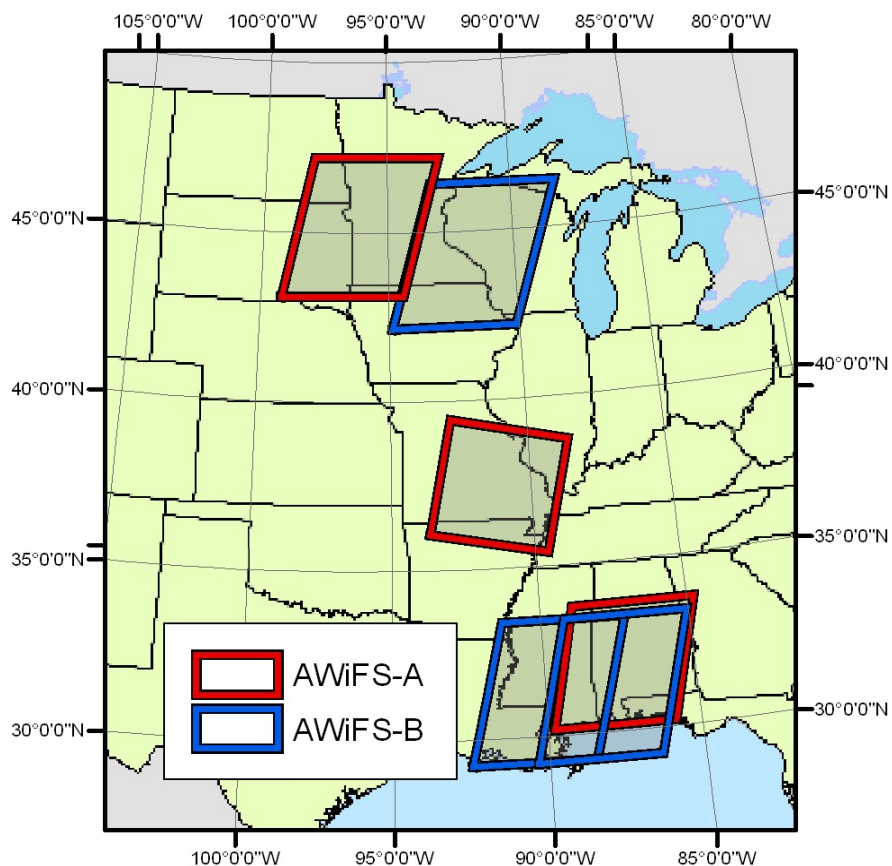
² Federal Geographic Data Committee, 1998. *Geospatial Positioning Accuracy Standards – Part 3: National Standard for Spatial Data Accuracy*. FGDC-STD-007.3-1998. Subcommittee for Base Cartographic Data. 28 p. <http://www.fgdc.gov/standards/projects/FGDC-standards-projects/accuracy/part3/chapter3>.



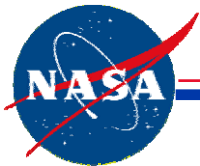
Characterized Scenes

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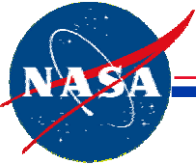
Distribution of Scenes



Acquisition	Camera
270-36-C 14 AUG 2004	AWiFS-A
277-42-C 5 MAR 2005	AWiFS-A
282-50-C 17 JAN 2005	AWiFS-A
270-36-D 14 AUG 2004	AWiFS-B
276-47-D 24 MAR 2005	AWiFS-B
278-47-D 27 APR 2005	AWiFS-B



Methods



Check Point Error

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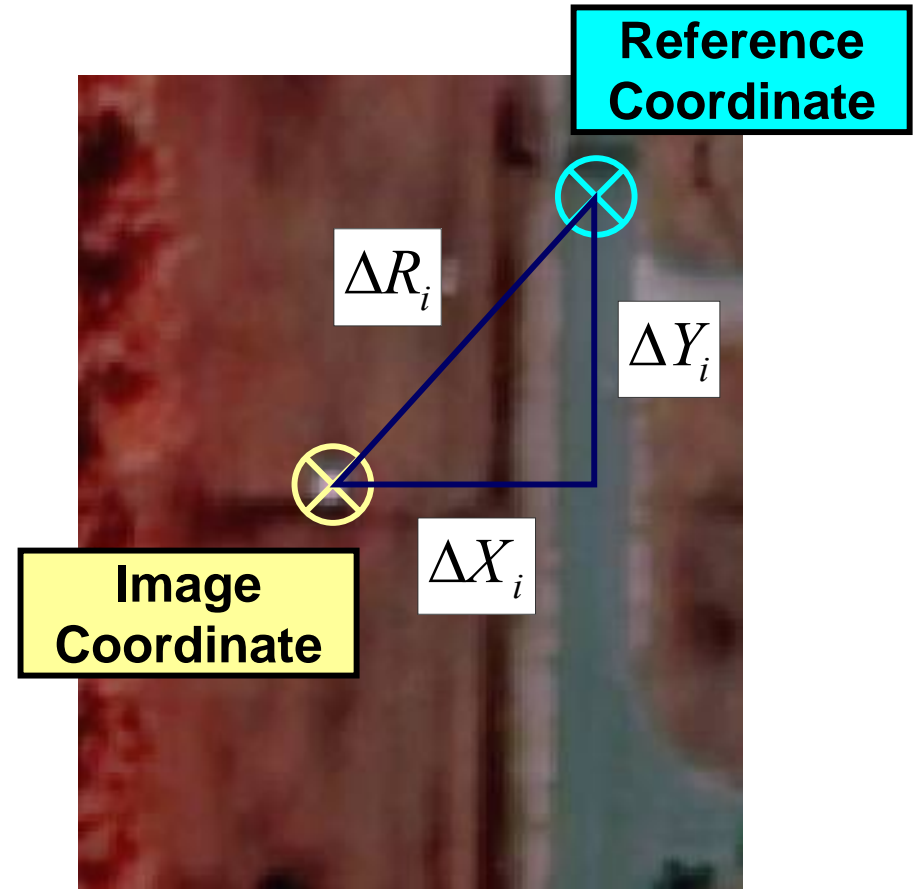
- Check Point Error – differences between image and reference coordinates

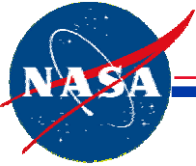
$$\Delta X_i = X_{image,i} - X_{reference,i}$$

$$\Delta Y_i = Y_{image,i} - Y_{reference,i}$$

- Check point error radial magnitude calculated by

$$\Delta R_i = \sqrt{\Delta X_i^2 + \Delta Y_i^2}$$





Sources of Error

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- Assessment Error
 - Ground Control Error
 - Pointing
 - Measurement
 - Analyst Error
 - Pointing
- Product Error (potential)
 - Spatial Resolution
 - Pointing (Displacement)
 - Azimuth
 - Scale
 - Orthogonality
 - Other product distortion
 - Terrain effects

“Pointing error” for surveyors & analysts indicates the errors these individuals have in picking their target

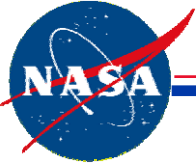
random error

“Measurement error” for ground control indicates the error inherent in the measuring instrument or system (in this case, the GPS)

constant systematic error

“Pointing error” for a geosensing system indicates the constant separation between estimated target coordinates and actual target coordinates

functional systematic error



Error Model: Primary Components

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- The error model chosen for generalized assessment

$$X_{image} = X + \varepsilon \quad \text{where} \quad \varepsilon = \varepsilon_{constant} + \varepsilon_{zero-mean}$$

- Horizontal Bias – an estimate of the constant error, designated here as μ_H , is the magnitude of the vector sum of the average error in the X and the Y

$$\mu_H = \sqrt{(\overline{\Delta X})^2 + (\overline{\Delta Y})^2}$$

- Circular Standard Error – an estimate of the zero-mean circular equivalent error valid even for elliptical error distributions with minimum to maximum error ratios as low as 0.6

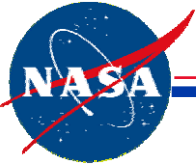
$$\sigma_C \cong \frac{\sigma_{\Delta X} + \sigma_{\Delta Y}}{2} \quad \text{where} \quad \sigma_{\Delta X} = \sqrt{\frac{\sum (\Delta X_i - \overline{\Delta X})^2}{n-1}} \quad \& \quad \sigma_{\Delta Y} = \sqrt{\frac{\sum (\Delta Y_i - \overline{\Delta Y})^2}{n-1}}$$

Ager (2004)¹ used the horizontal error defined on the right, but Greenwalt and Shultz (1962)² found this to be invalid for minimum to maximum error ratios less than 0.8

$$\sigma_H = \sqrt{\frac{(\sigma_{\Delta X}^2 + \sigma_{\Delta Y}^2)}{2}}$$

¹ Ager, T.P., 2004. *An Analysis of Metric Accuracy Definitions and Methods of Computation*. NIMA InnoVision white paper.

² Greenwalt, C.R., and M.E. Shultz, 1962. *Principles of Error Theory and Cartographic Applications*. ACIC Technical Report No. 96, United States Air Force, Aeronautical Chart and Information Center, St. Louis, Missouri, 98 pp.



Error Model: Zero-Mean Components

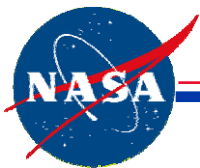
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- The zero-mean error model

$$\varepsilon_{zero-mean} = \varepsilon_{along-track}(u) + \varepsilon_{across-track}(u) + \varepsilon_{non-systematic}$$

Where u is the across-track position

- It is important to examine the zero-mean error more closely in the case of AWiFS because the error distribution clearly departs from a simple circular error distribution with a horizontal bias
- The along and across track errors, while functionally more complex than horizontal bias, are still systematic errors that are largely correctable
- The non-systematic error represents random error and harder to model errors such as terrain distortion; this error is the most difficult (costliest) to correct

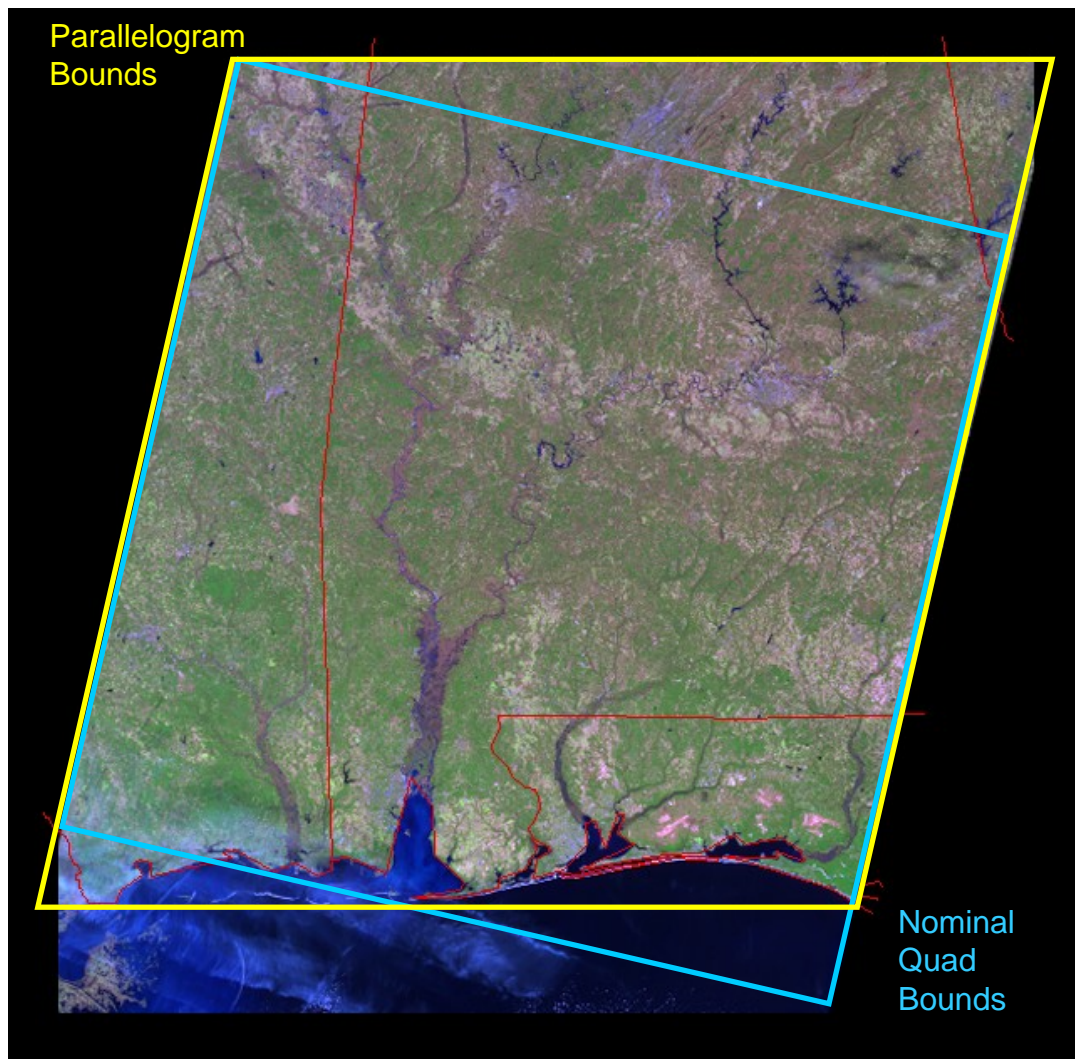


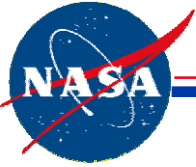
Defining Area of Analysis

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- Area of analysis defined as the “parallelogram”* with the largest area useful for analysis rather than the nominal AWiFS quad boundaries

* East and west bounds are not perfectly parallel.

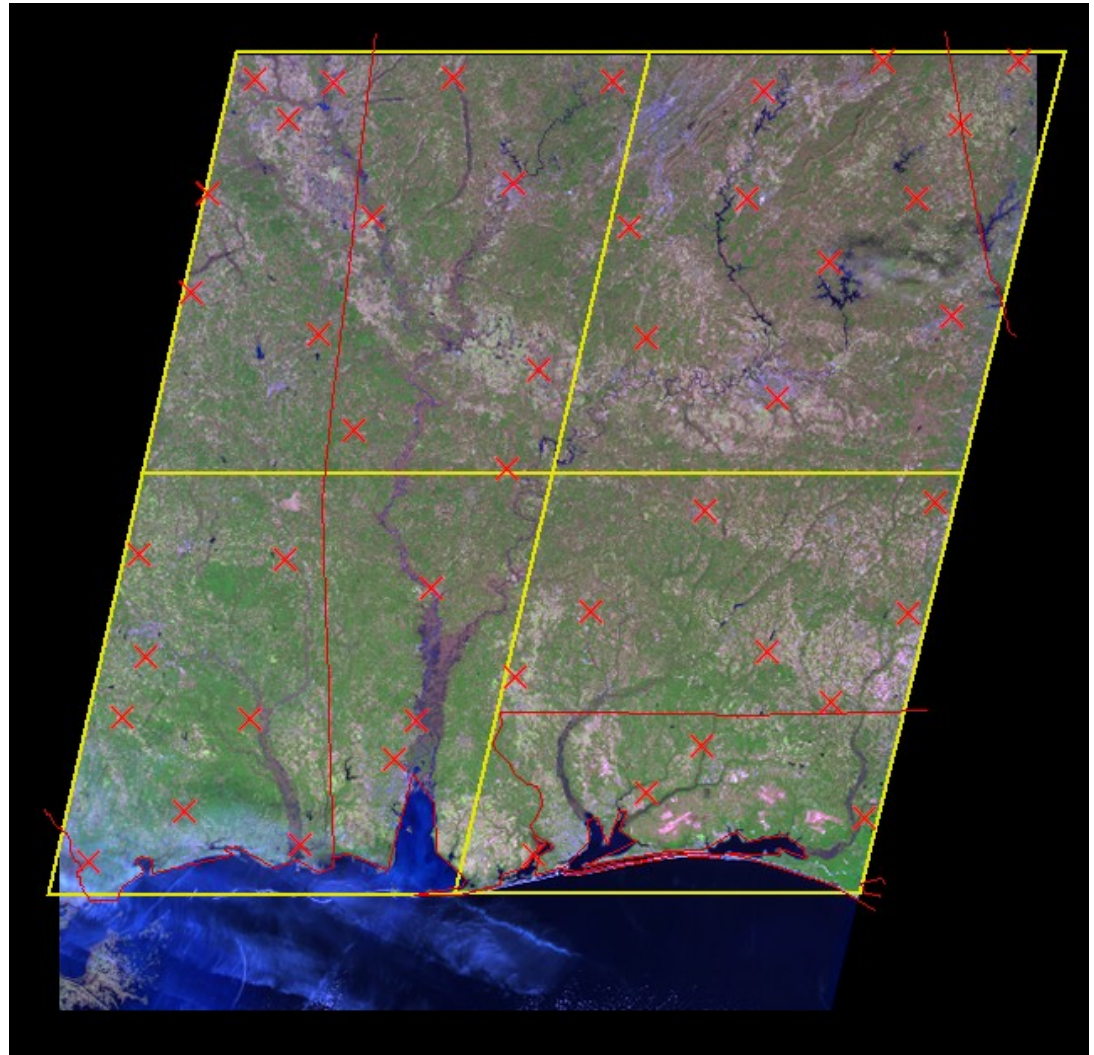


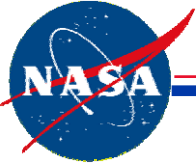


Methods: Selecting & Distributing Check Points

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- Area of analysis divided into quadrants and check points selected in each
 - Selected 45 to 50 points (NSSDA minimum = 20)
 - At least 20% in each quadrant
 - *Did not strictly maintain point separation of 10% of diagonal*

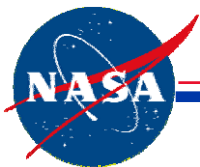




Data Collection Notes

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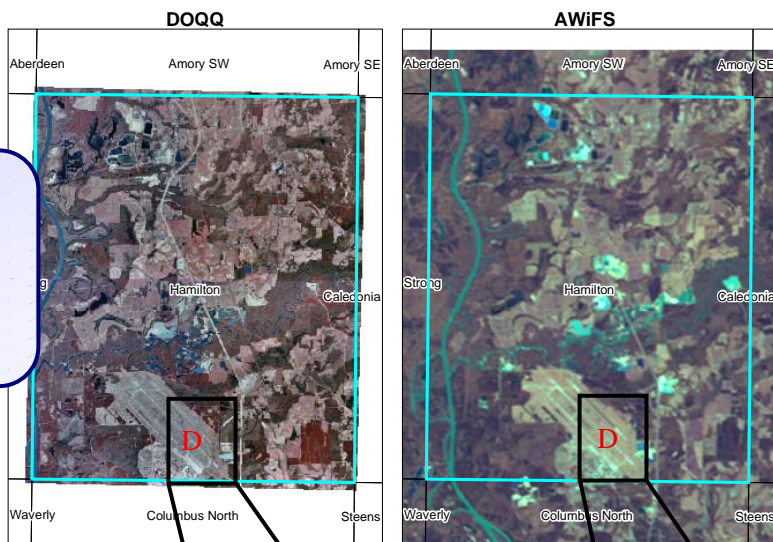
- Tentative check points were collected in ESRI ArcMap using heads-up digitizing to a point shapefile overlaying the AWiFS source image
- All check point data were collected in the AWiFS scene-specific Lambert Conformal Conic projection
- Reference images (typically DOQQs) were identified and added to the ArcMap project; on-the-fly re-projections by ArcMap were found to be sufficient
- Reference images were searched for tentative check points identified in the AWiFS source image
 - If a tentative point was missing or indistinct in the reference image, both images were searched for an alternative
 - No more than one check point was used per reference image



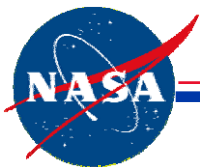
Example AWiFS Check Point

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Obtained DOQQ containing point
(DOQQ RMSE assumed ~5 m)

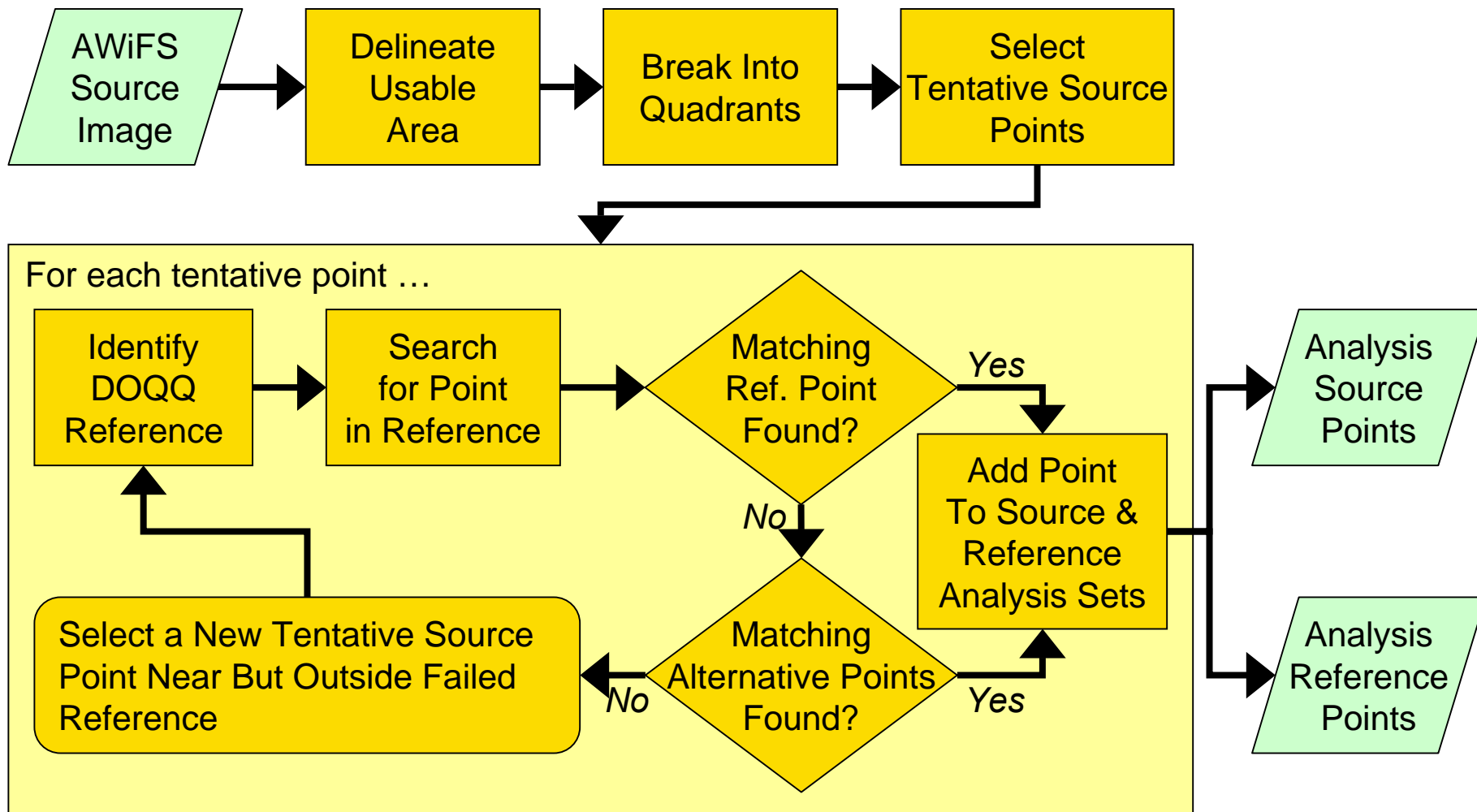


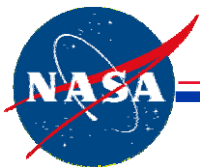
Extracted AWiFS
image coordinate
and DOQQ
reference
coordinate



Check Point Collection Flow

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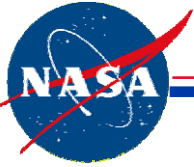




Check Point Blunder Detection

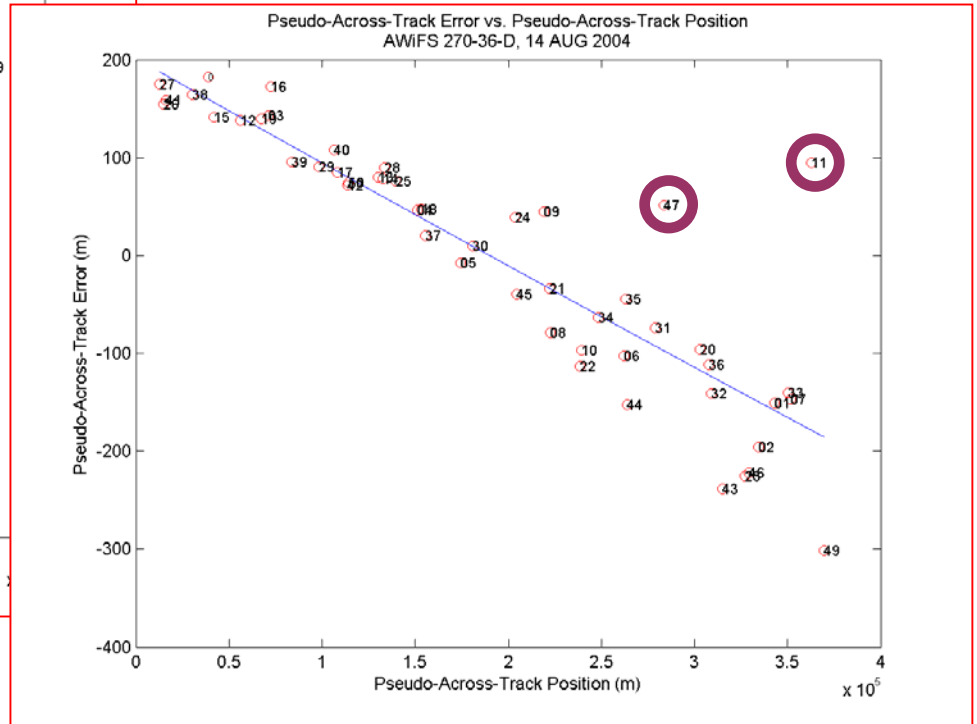
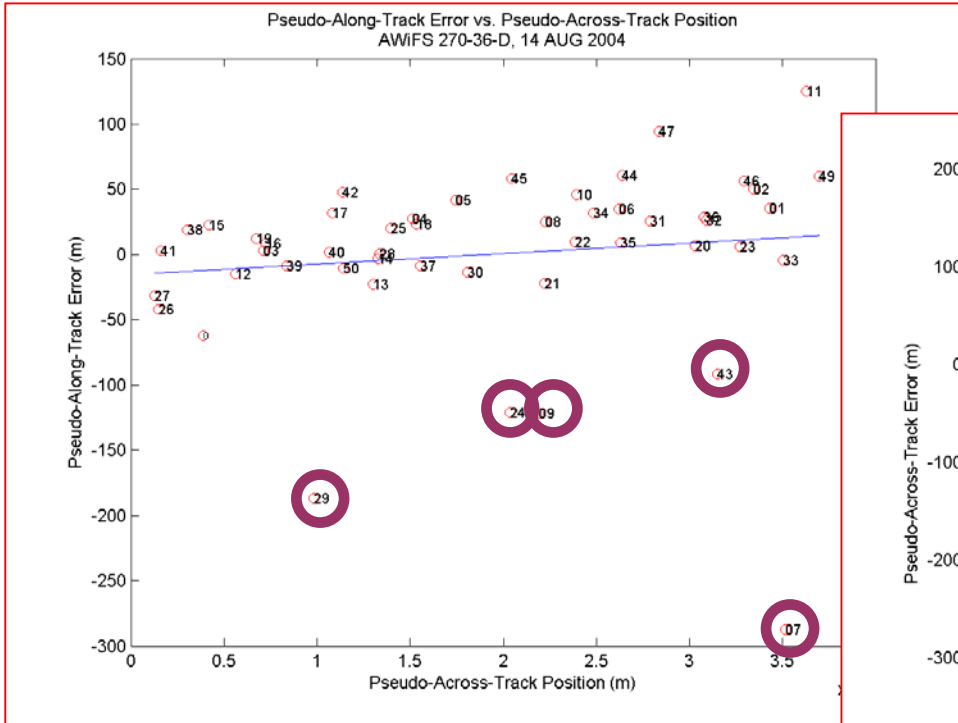
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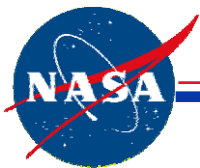
- Transform the frame of reference for the check points from the AWiFS image projection to a quasi-satellite-path frame (approximate along track position: positive Y, approximate across track position: positive X)
 - Shift frame origin to minimum X, minimum Y of analysis area
 - Rotate frame so that satellite-path direction (approximated by average azimuth of east and west bounds of analysis area) is up
- Compute residuals from difference in source and reference coordinates of check points
- Compute zero-mean residuals by subtracting overall means from residuals
- Plot both components of zero-mean residuals vs. across track check point positions
 - Along track zero-mean residuals vs. across track position
 - Across track zero-mean residuals vs. across track position
- Observe the plots to determine if systematic relationship between position and error exists
- If systematic relationship exists, determine if some of the check points depart from a clear trend (this is a subjective choice in the 2005 analysis)
- Re-submit any out-of-step points to be re-evaluated as check points
- Repeat check point blunder detection



Before Blunder Detection

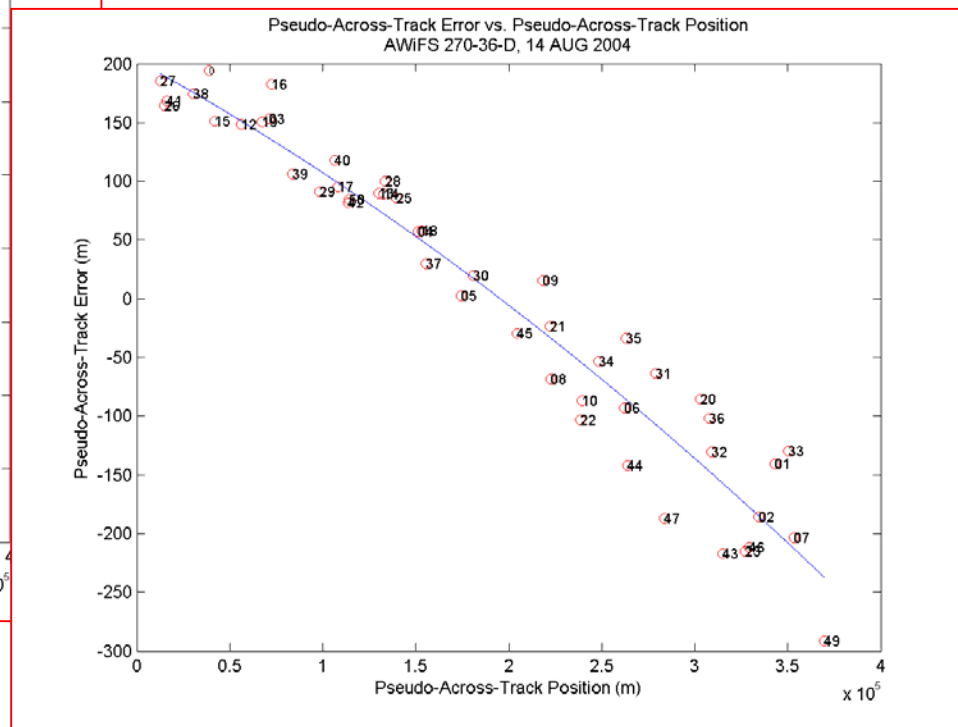
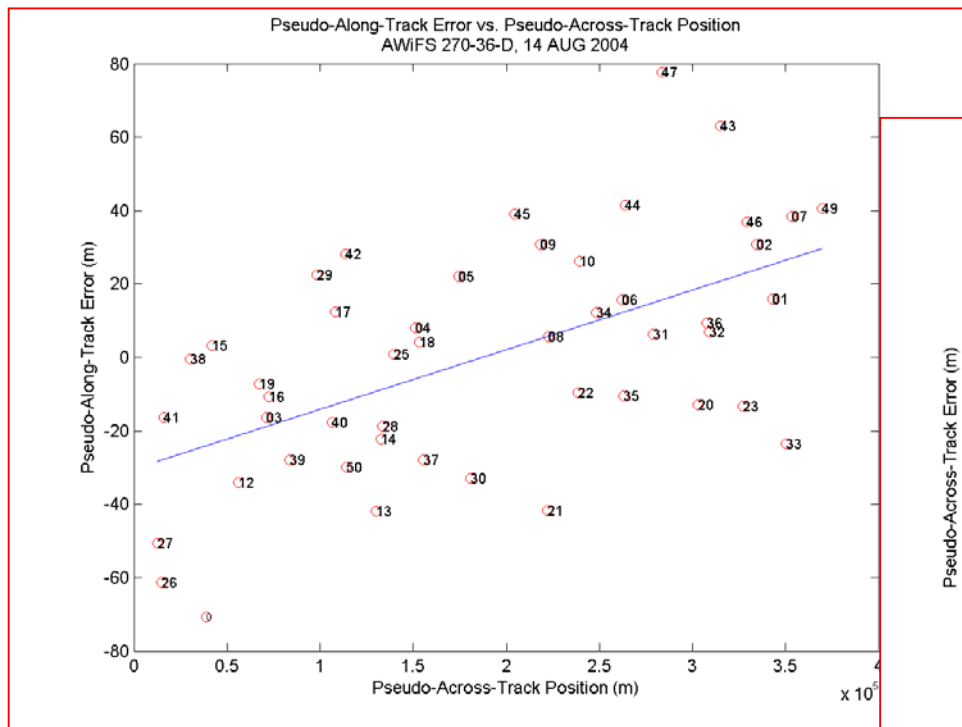
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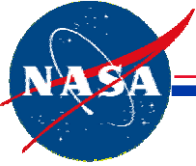




After Blunder Detection

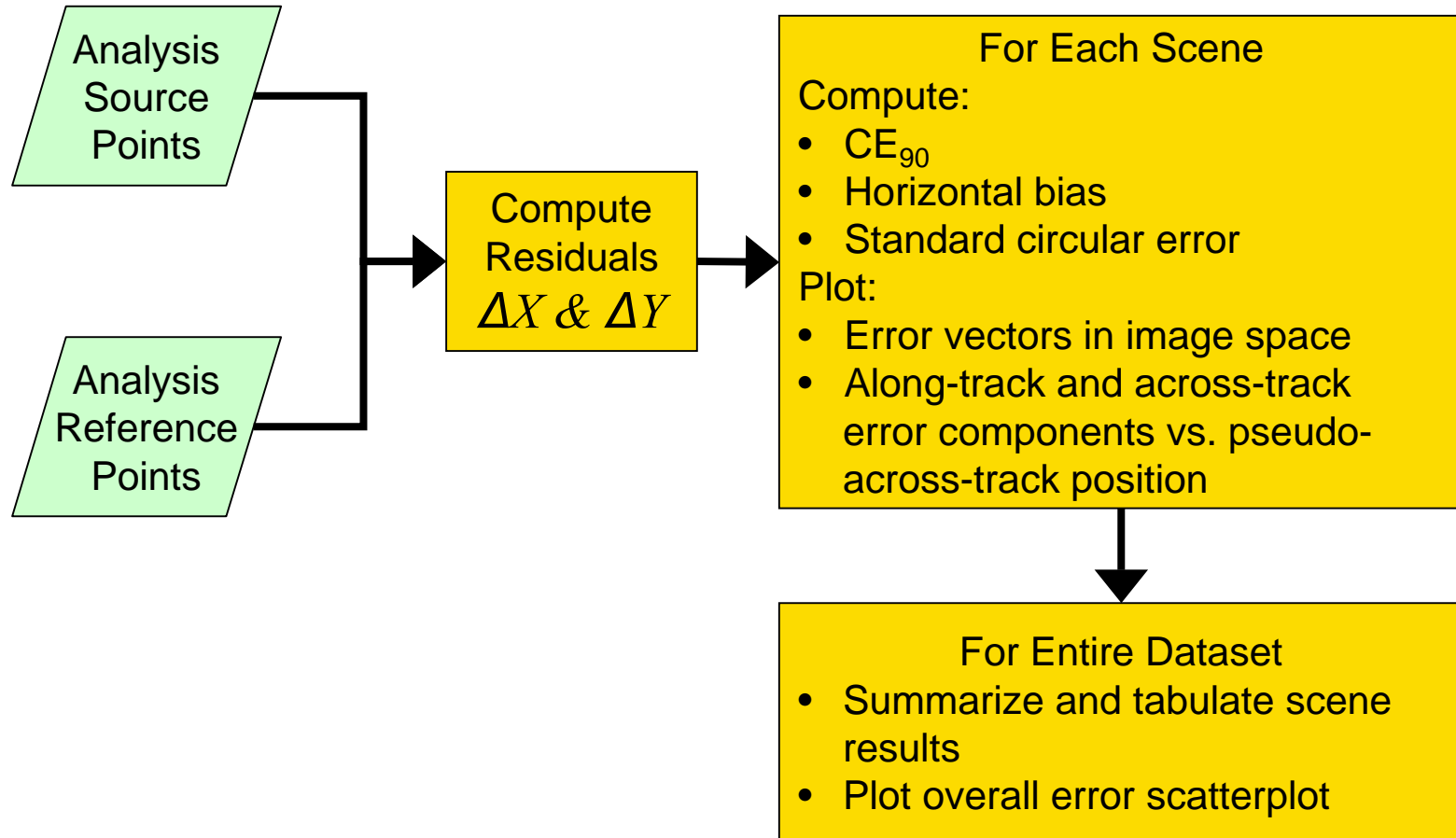
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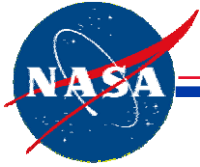




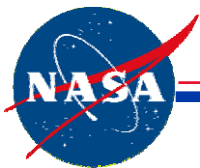
Analyses Flow

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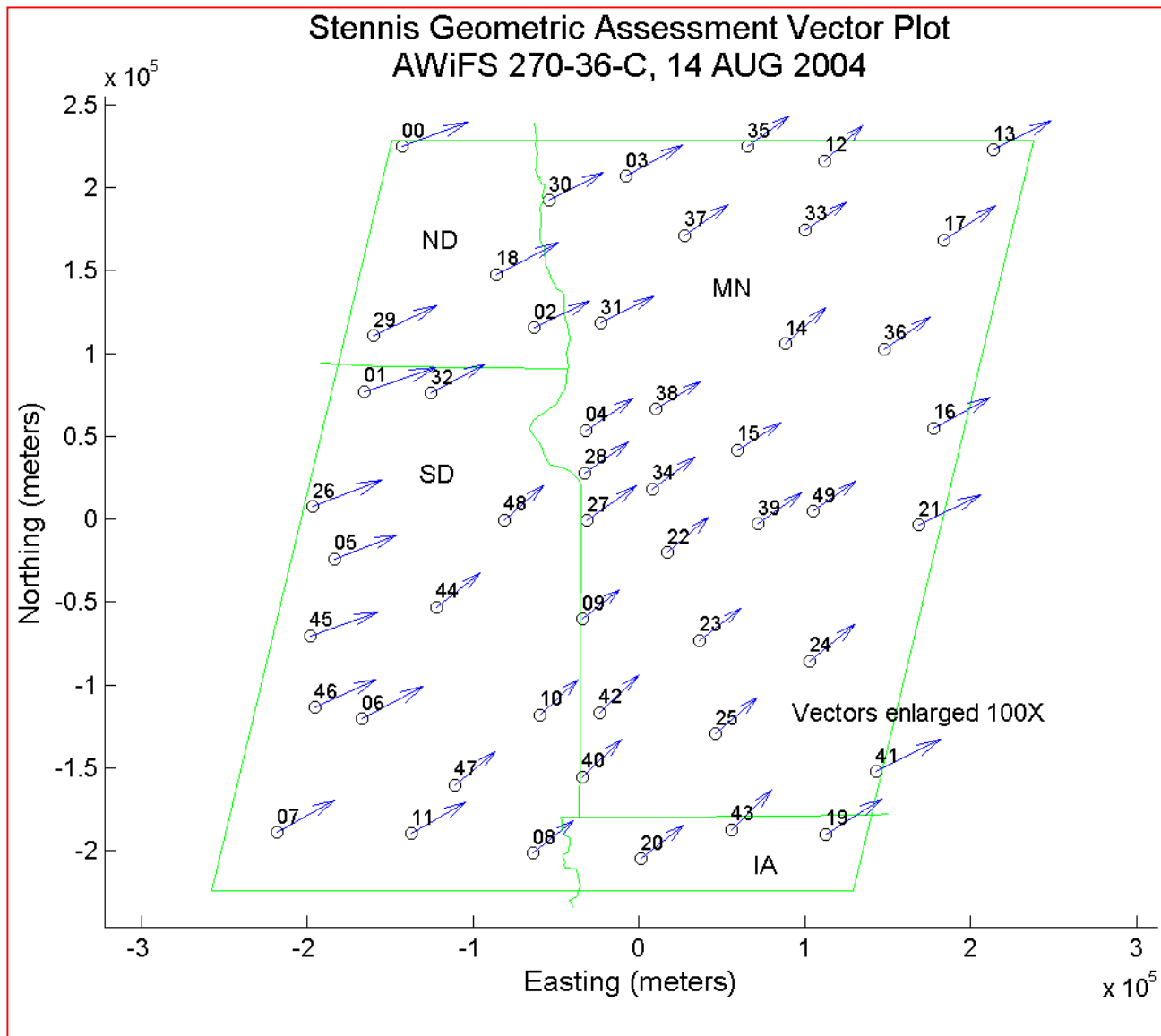
Results

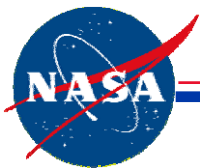


Individual Scene Results

AWiFS A (1)

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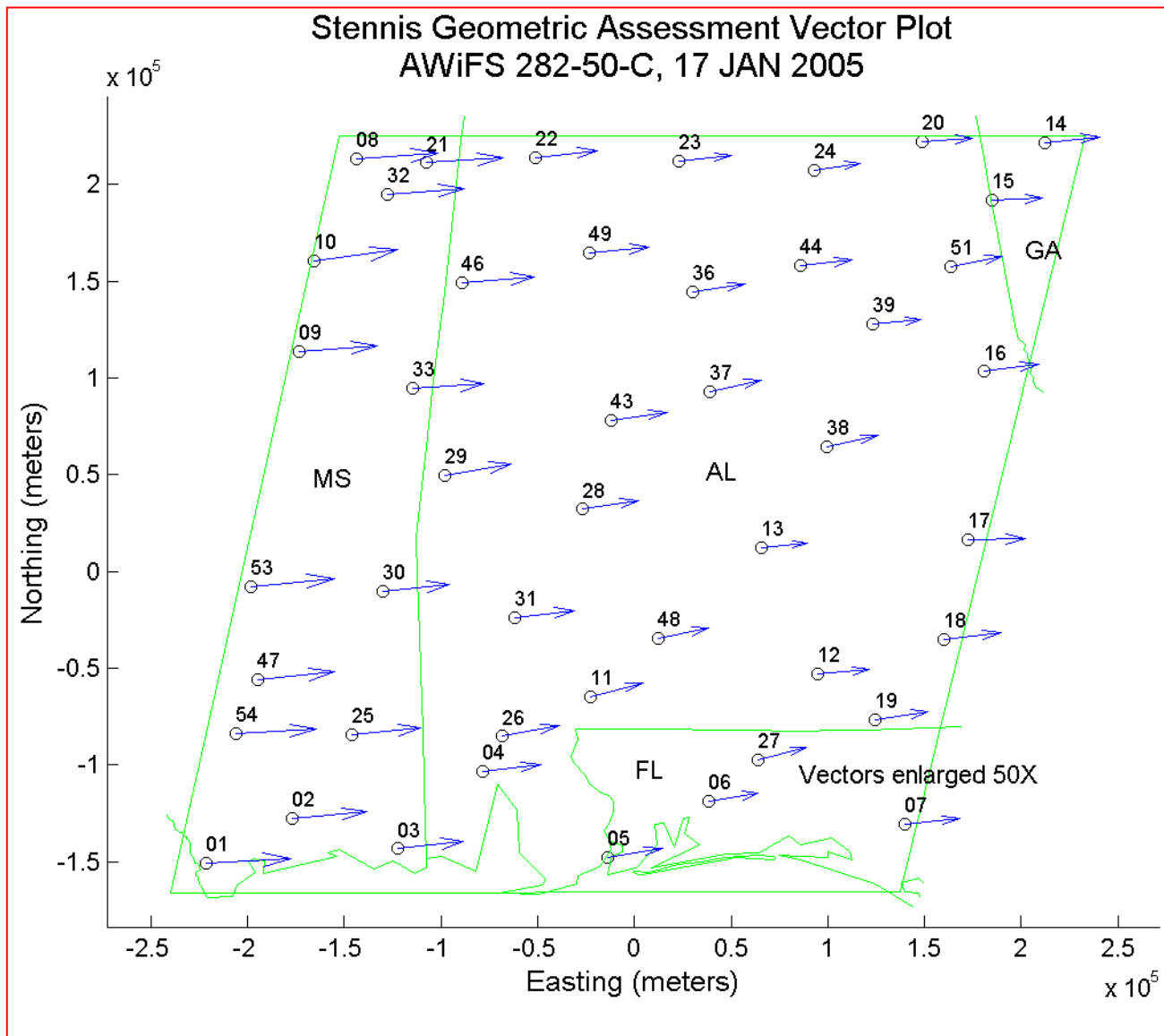


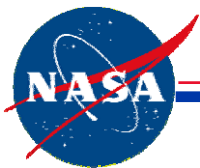


Individual Scene Results

AWiFS A (2)

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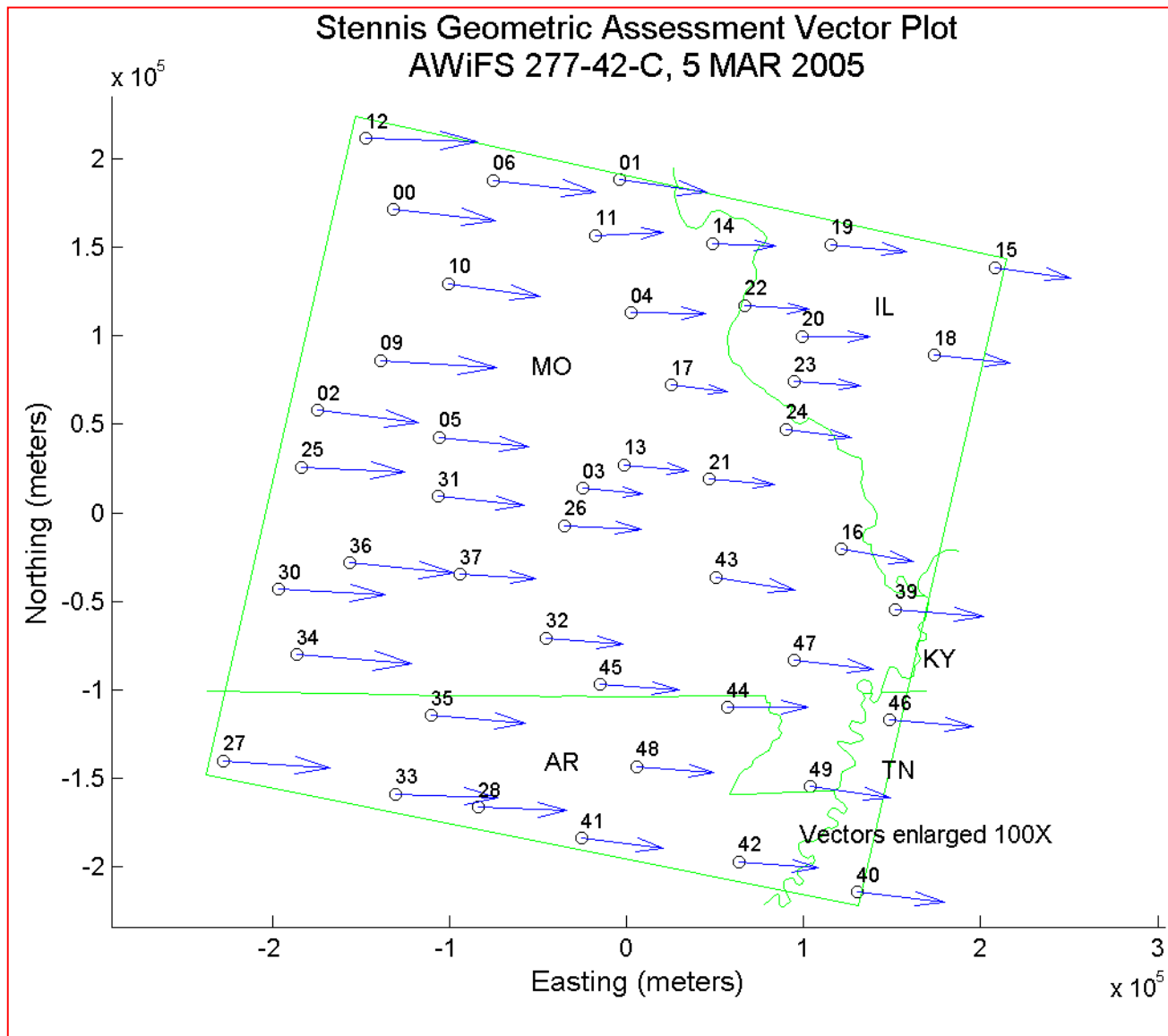


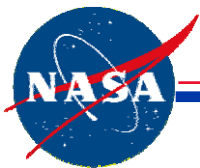


Individual Scene Results

AWiFS A (3)

Stennis Space Center

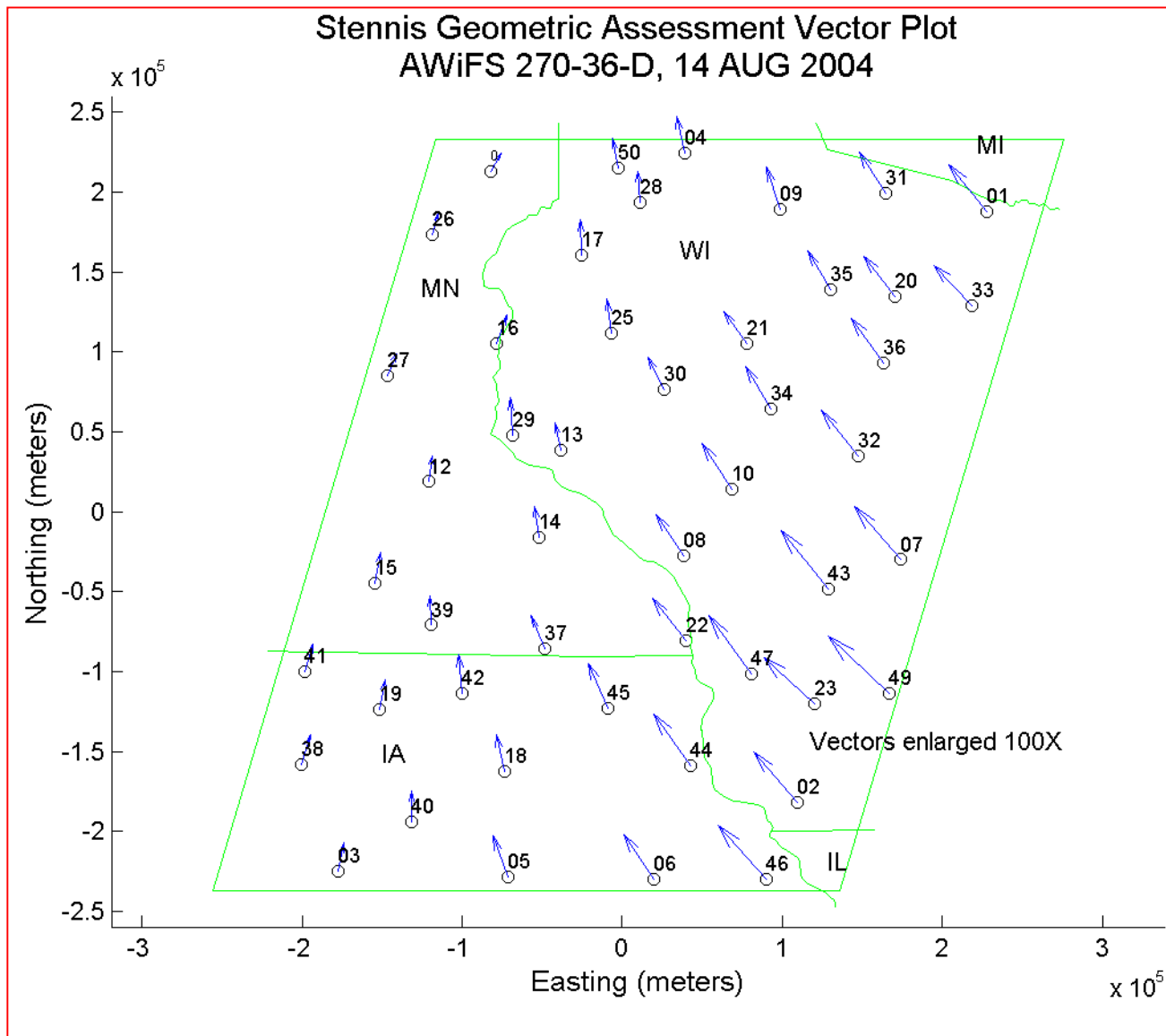


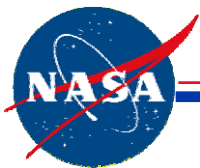


Individual Scene Results

AWiFS B (1)

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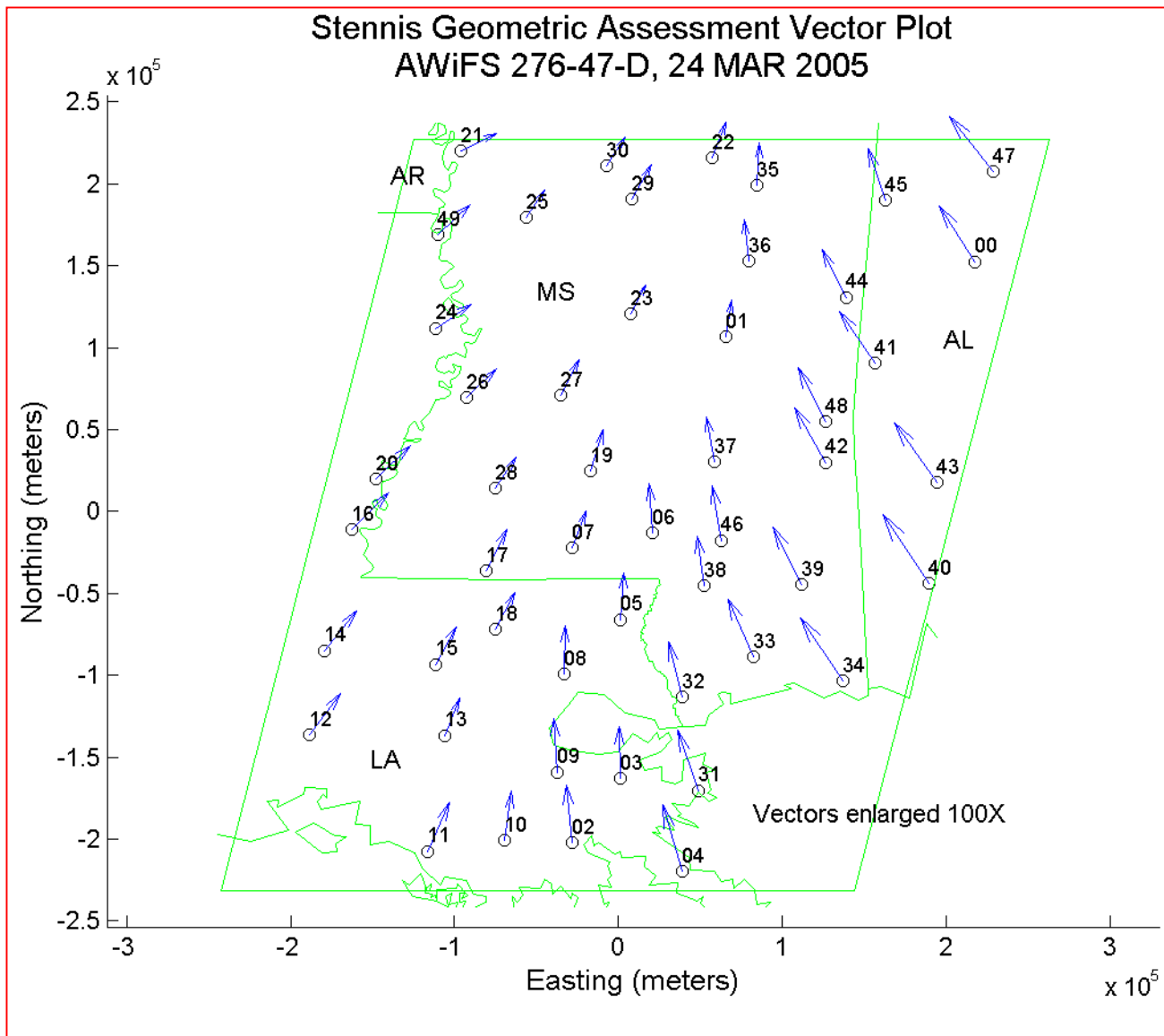


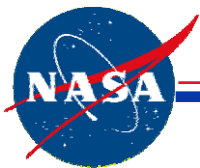


Individual Scene Results

AWiFS B (2)

Stennis Space Center

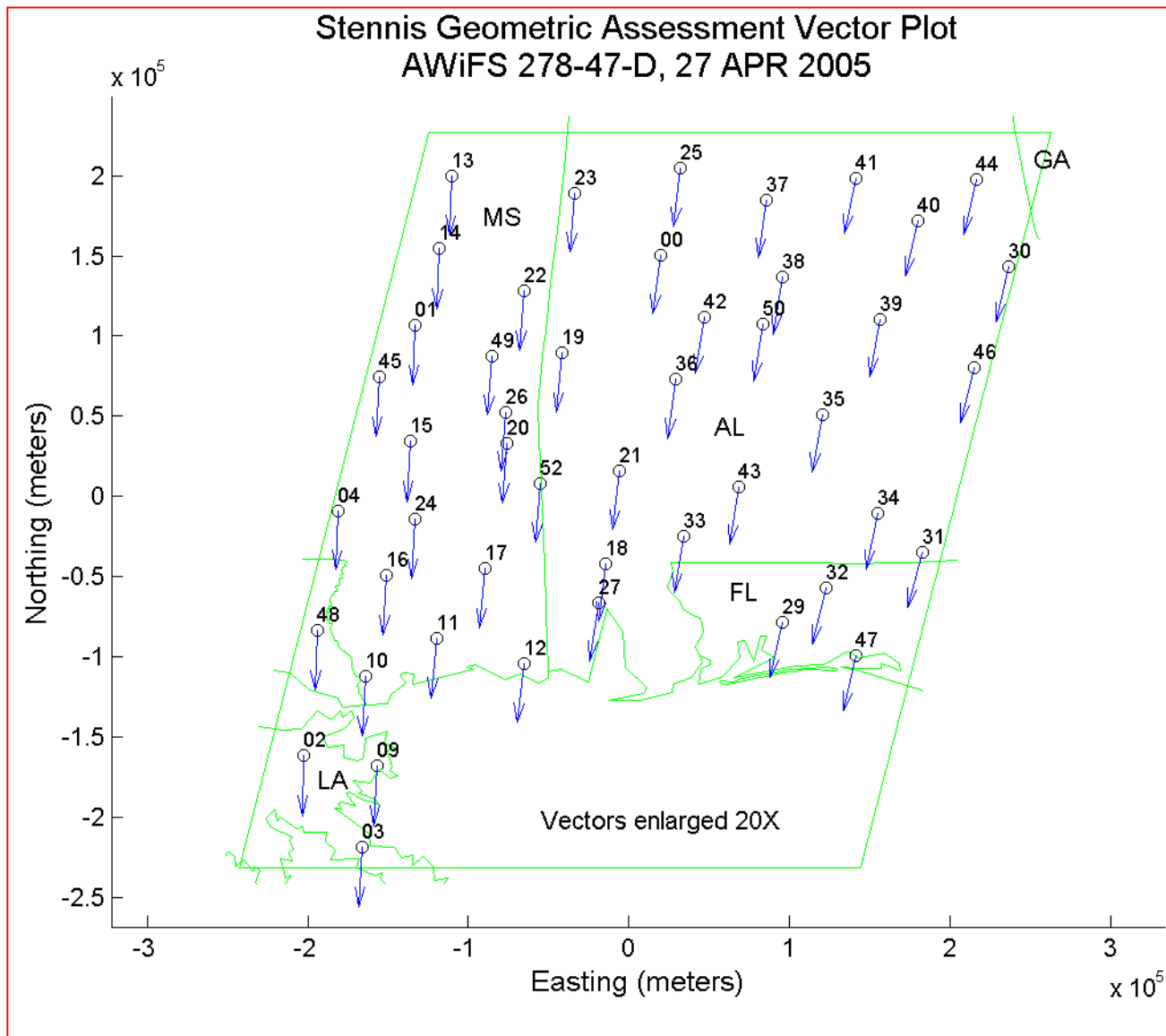


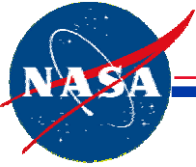


Individual Scene Results

AWiFS B (3)

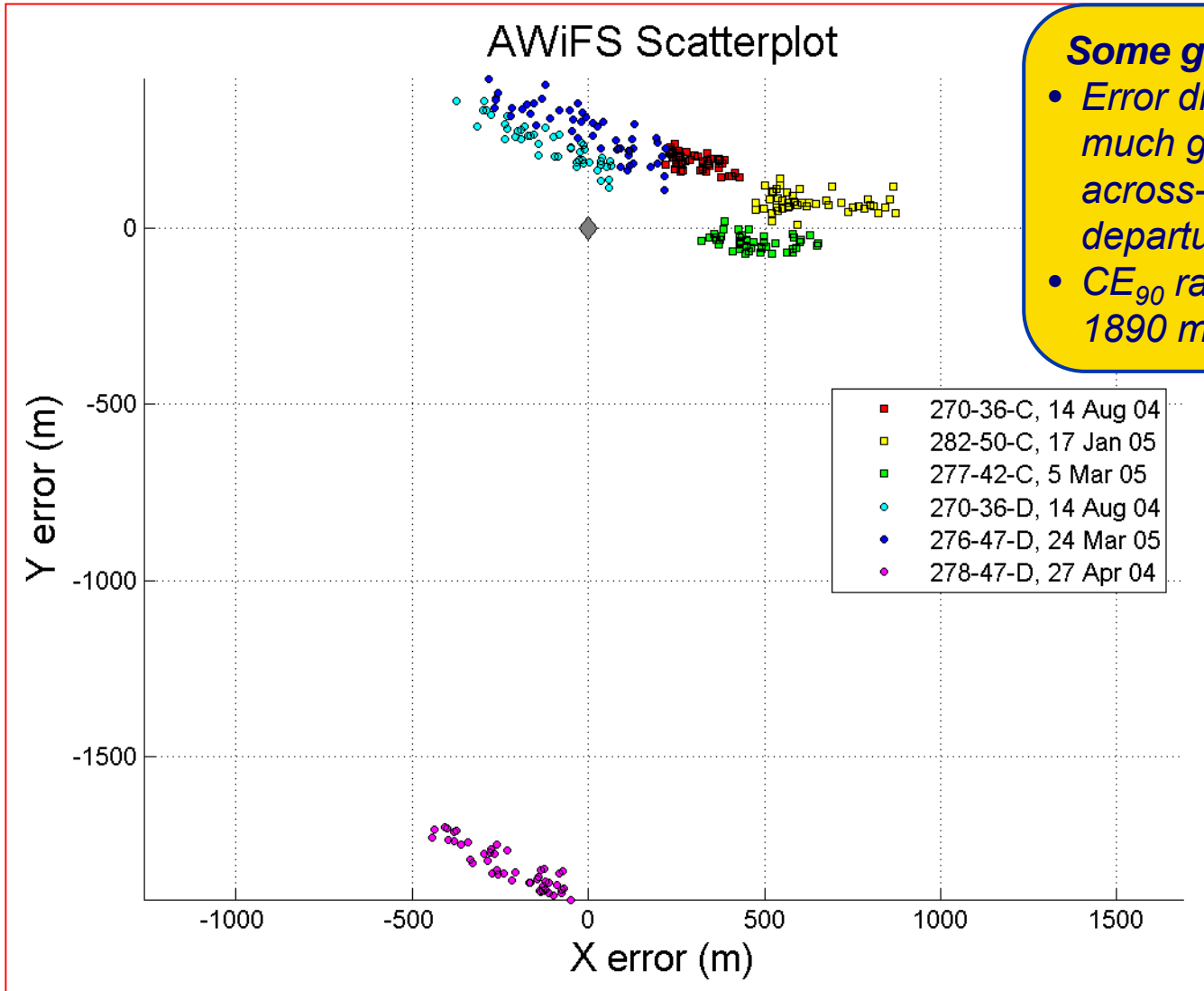
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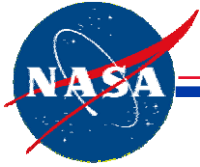
Overall Scatter

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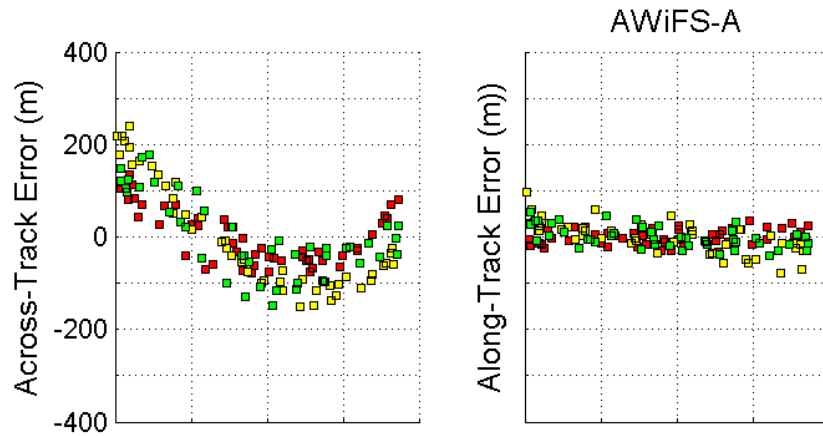
Some general characteristics:

- Error distributions showed much greater spread in the across-scan direction (large departure from circularity)
- CE_{90} ranged from 410 m to 1890 m



Zero-Mean Errors by Sample

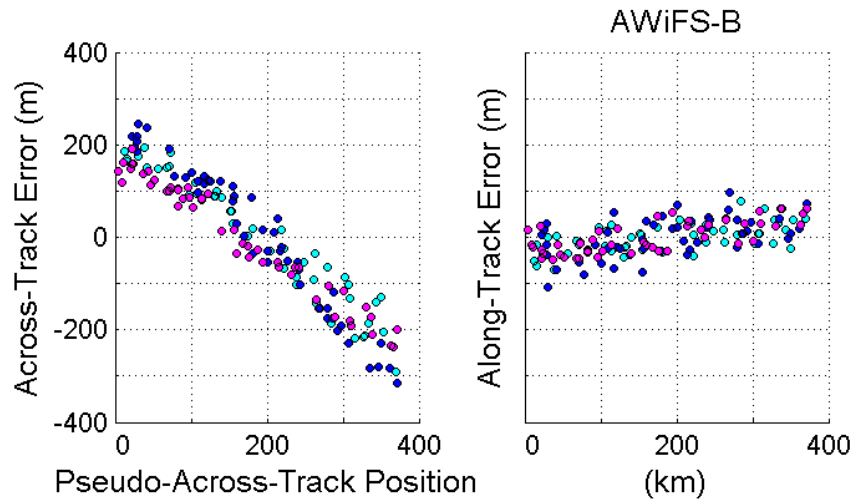
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There was little correlation between sample position and error in the along-scan direction

- 270-36-C, 14 Aug 04
- 282-50-C, 17 Jan 05
- 277-42-C, 5 Mar 05

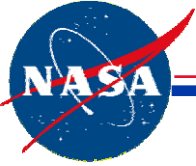
Across-scan errors for AWiFS-A have a 2nd order relationship with sample position



- 270-36-D, 14 Aug 04
- 276-47-D, 24 Mar 05
- 278-47-D, 27 Apr 04

Standard products appear to be correctable with simple polynomial rectification

Across-scan errors for AWiFS-B have a linear relationship with sample position



Summary of Results

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AWiFS Product	Acquisition Date	Sub-scene	Horizontal Bias (m)	Circular Std. Error (m)	Empirical CE ₉₀ (m)
AWiFS-A Geo	14-Aug-2004	270-36-C	354	41	423
	17-Jan-2005	282-50-C	636	74	823
	5-Mar-2005	277-42-C	475	54	599
AWiFS-B Geo	14-Aug-2004	270-36-D	262	92	438
	24-Mar-2005	276-47-D	274	110	413
	27-Apr-2005	278-47-D	1826	89	1887

- The mean CE₉₀ of AWiFS Geo images characterized was 760 m
 - Ranged from 423 m to 1887 m
- Lutes (2005) analyzed 8 AWiFS scenes and found a mean CE₉₀ of 610 m
 - Ranged from 294 m to 756 m
- Both analyses are in general agreement with the exception of the 27 APR 2005 results in the SSC study
- Both analyses show generally grosser error than the estimate of 320 m stated in the *IRS-P6 Data User's Manual* (2003)¹

¹ National Remote Sensing Agency, 2003. *IRS-P6 Data User's Manual*. Edition No. 1. IRS-P6/NRSA/NDC/HB-10/03, Department of Space, Govt. of India. October, 142 p. http://www.euromap.de/download/P6_data_user_handbook.pdf (accessed February 6, 2006).