IA_Eastern_2019- WUID 300007

Report Produced for U.S. Geological Survey

USGS Contract: G16PC00020

Task Order: 140G0219F0101

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ATTACHMENTS

Appendix A (Leading Edge Geomatics): GPS Processing Reports

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1. EXECUTIVE SUMMARY

This task order requests a spring/summer 2019 leaf-off lidar survey to be collected over a primary area of interest (AOI) in the state of Iowa of approximately 14,724 square miles, including the counties of: Winneshiek, Allamakee, Chickasaw, Bremer, Fayette, Clayton, Black Hawk, Buchanan, Delaware, Dubuque, Benton, Linn, Jones, Jackson, Johnson, Cedar, Clinton, Scott, Muscatine, Washington, Louisa, Henry, Des Moines, and Lee. Some overlap of data onto surrounding counties and neighboring Illinois is expected. This project will support the National Resources Conservation Service (NRCS) high resolution elevation enterprise program, the Iowa Department of Agriculture and Land Stewardship (IDALS) Iowa Flood Plain program, and the 3DEP mission.

Lidar data were processed and classified according to project specifications. Detailed breaklines and bare-earth Digital Elevation Models were produced for the project area. Project components were formatted based on a tile grid with each tile covering an area 1,000 m by 1,000 m. A total of 38,741 tiles were produced for the project, providing approximately 14,724 square miles of coverage. A total of 10,683 tiles were produced for WUID 300007, providing approximately 4,088 sq. miles of coverage.

1.1 Project Team

Dewberry served as the prime contractor for the project. In addition to project management, Dewberry was responsible for LAS classification, all lidar products, breakline production, digital elevation model (DEM) production, and quality assurance.

Dewberry completed the ground survey for the project and delivered surveyed checkpoints. The task was to acquire surveyed checkpoints for the project to use in independent testing of the vertical accuracy of the lidar-derived surface model and to acquire surveyed ground control points for use in calibration activities. Dewberry also verified the GPS base station coordinates used during lidar data acquisition.

Leading Edge Geomatics and Aerial Services, Inc. completed lidar data acquisition for WUID 300007. Leading Edge Geomatics calibrated their acquisition area for this WUID, Dewberry calibrated Aerial Services, Inc acquisition for this WUID.

1.2 Project Area

The block area is shown in figure 1. WUID 300007 contains 10,683 1,000 m by 1,000 m tiles. The project tile grid contains 38,741 1,000 m by 1,000 m tiles.

IA_Eastern_300007_2019

Figure 1. Project map and tile grid.

1.3 Coordinate Reference System

Data produced for the project are delivered in the following spatial reference system:

Horizontal Datum:	North American Datum of 1983 with the 2011 Adjustment (NAD 83 (2011))
Vertical Datum:	North American Vertical Datum of 1988 (NAVD88)
Geoid Model:	Geoid18
Coordinate System:	UTM Zone 15N
Horizontal Units:	Meters
Vertical Units:	Meters

1.4 Project Deliverables

The deliverables for the block are as follows:

1. Project Extents (Esri SHP)
2. Classified Point Cloud (tiled LAS)
3. Flightline Data (file GDB)
4. Intensity Images (tiled, 8-bit gray scale, GeoTIFF format)
5. Breakline Data (file GDB)
6. Bare Earth Surface (tiled raster DEM, GeoTIFF format)
7. Swath Separation Images
8. Interswath Polygons
9. Intraswath Polygons
10. Metadata (XML)
11. Confidence Polygons
12. Block Report

1.5 Dewberry Production Workflow Diagram

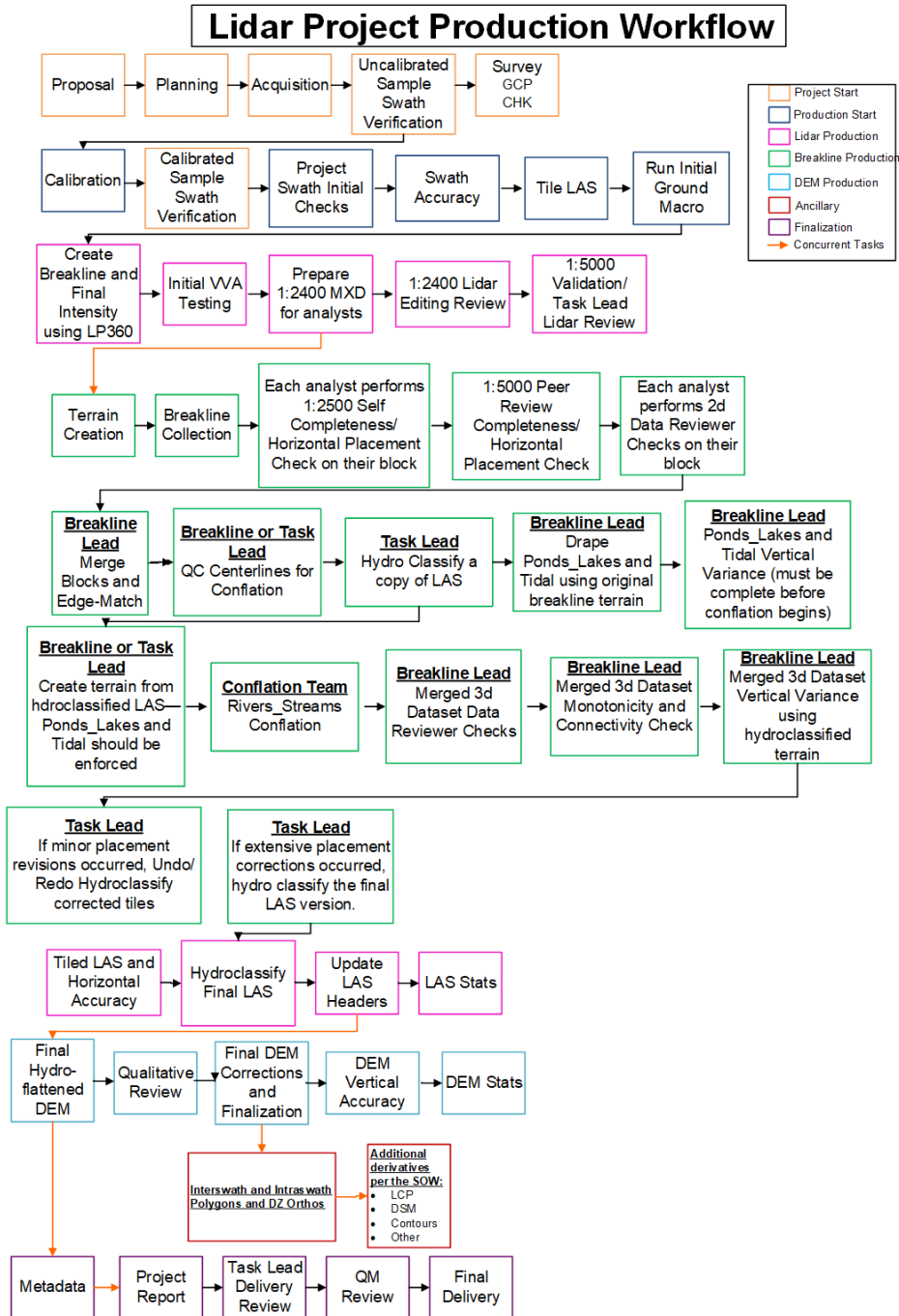The diagram below outlines Dewberry's standard lidar production workflow.

Lidar Project Production Workflow

☐	Project Start
☐	Production Start
☐	Lidar Production
☐	Breakline Production
☐	DEM Production
☐	Ancillary
☐	Finalization
→	Concurrent Tasks

Proposal → Planning → Acquisition → Uncalibrated Sample Swath Verification → Survey GCP CHK

Calibration → Calibrated Sample Swath Verification → Project Swath Initial Checks → Swath Accuracy → Tile LAS → Run Initial Ground Macro

Create Breakline and Final Intensity using LP360 → Initial VVA Testing → Prepare 1:2400 MXD for analysts → 1:2400 Lidar Editing Review → 1:5000 Validation/ Task Lead Lidar Review

Terrain Creation → Breakline Collection → Each analyst performs 1:2500 Self Completeness/ Horizontal Placement Check on their block → 1:5000 Peer Review Completeness/ Horizontal Placement Check → Each analyst performs 2d Data Reviewer Checks on their block

Breakline Lead Merge Blocks and Edge-Match → **Breakline or Task Lead** QC Centerlines for Conflation → **Task Lead** Hydro Classify a copy of LAS → **Breakline Lead** Drape Ponds_Lakes and Tidal using original breakline terrain → **Breakline Lead** Ponds_Lakes and Tidal Vertical Variance (must be complete before conflation begins)

Breakline or Task Lead Create terrain from hdroclassified LAS—Ponds_Lakes and Tidal should be enforced → **Conflation Team** Rivers_Streams Conflation → **Breakline Lead** Merged 3d Dataset Data Reviewer Checks → **Breakline Lead** Merged 3d Dataset Monotonicity and Connectivity Check → **Breakline Lead** Merged 3d Dataset Vertical Variance using hydroclassified terrain

Task Lead If minor placement revisions occurred, Undo/ Redo Hydroclassify corrected tiles   **Task Lead** If extensive placement corrections occurred, hydro classify the final LAS version.

Tiled LAS and Horizontal Accuracy → Hydroclassify Final LAS → Update LAS Headers → LAS Stats

Final Hydro-flattened DEM → Qualitative Review → Final DEM Corrections and Finalization → DEM Vertical Accuracy → DEM Stats

Interswath and Intraswath Polygons and DZ Orthos   **Additional derivatives per the SOW:** • LCP • DSM • Contours • Other

Metadata → Project Report → Task Lead Delivery Review → QM Review → Final Delivery

Figure 2. Dewberry's Lidar Production Workflow Diagram

2. LIDAR ACQUISITION REPORT – LEADING EDGE GEOMATICS

Dewberry elected to subcontract the lidar acquisition and calibration activities to Leading Edge. Leading Edge Geomatics was responsible for providing lidar acquisition, calibration, and delivery of lidar data files to Dewberry.

The lidar aerial acquisition for this WUID was conducted between December 7, 2019 to November 19, 2020.

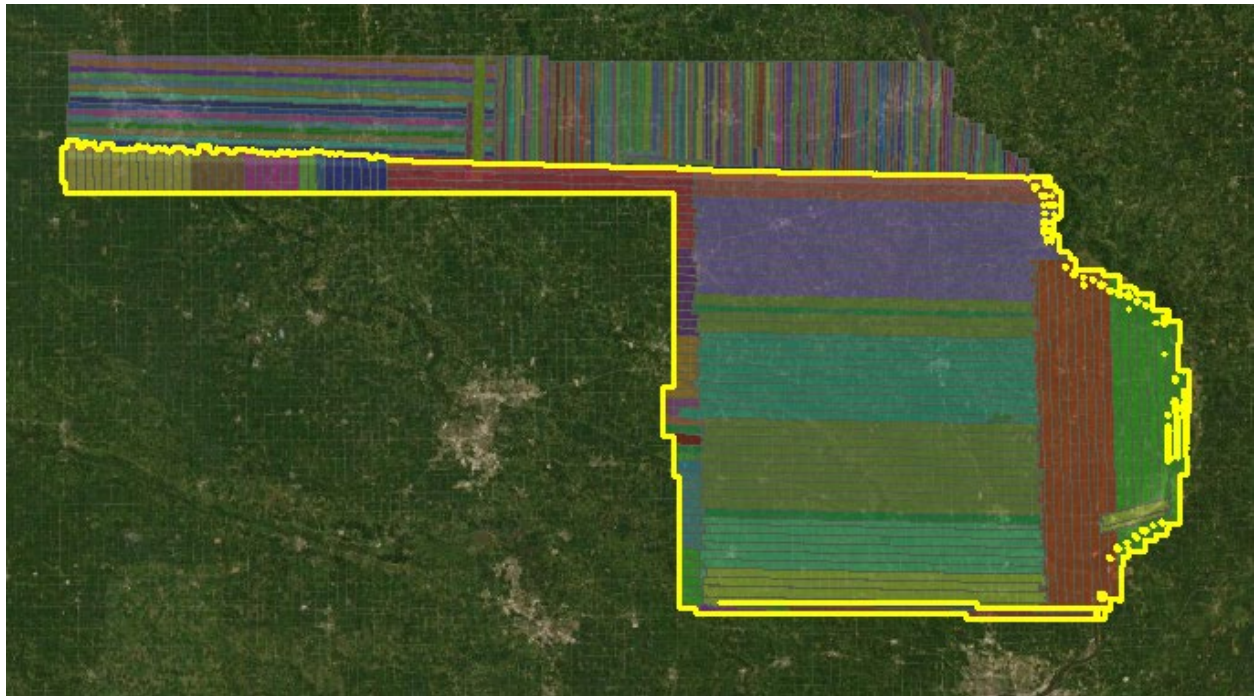## 2.1 Acquisition Extents

Figure 3 shows flightline vectors by lift.

Figure 3. WUID 300007 LEG swaths

2.2 Acquisition Summary

The Mississippi River runs along the eastern edge of the city of Maquoketa and Dubuque, Iowa as well as the surrounding area. Acquisition of the QL2 lidar within this region of the project was hampered by multiple delays. Dewberry worked closely with its subcontractors, the USGS, and its partners to monitor ground conditions and acquire data during optimal windows that met with all project requirements. Acquisition was to begin in the spring of 2019 but was halted due to snow on ground followed by Mississippi River flooding in May 2019 and increasing leaf-on conditions. Dewberry was permitted to restart acquisition in the fall of 2019 but was again hampered by poor ground conditions brought on by an unseasonably wet and warm fall resulting in a longer leaf-on period. Acquisition resumed in December of 2019 for a brief period before COVID-19 restrictions went into effect nationwide and added to further delays as all stakeholders began to follow and enact state and

federal guidelines surrounding the pandemic. Dewberry completed acquisition for this project in November of 2020, after communicating with USGS and local stakeholders on how best to proceed given the environmental conditions. The result of these varying delays, coupled with flooding events along the Mississippi River, have resulted in multiple temporal issues along adjoining swaths for this area of the project. Seasonal changes in the water levels, in addition to the localized flooding in some areas, required extra care and effort to determine the true banks of rivers and streams within this area. A "temporal" polygons shapefile is provided that identifies the areas affected by these temporal changes with this WUID delivery. Areas with low ground density and poor ground definition due to flooding, mostly along the banks of the Mississippi River, are delineated in a "low confidence" polygon shapefile.

2.3 Sensor Calibration and Boresight

The trajectory (.sbet) was processed using Applanix PosPac and raw swath data (.las) was produced using Reigl RiProcess. The boresight was calibrated and then analyzed. All deemed necessary corrections are then applied to the sensor orientation internal files. The initial points for each mission calibration are inspected for flight line errors, flight line overlap, slivers or gaps in the data, point data minimums, or issues with the lidar unit or GPS. Roll, pitch, and scanner scale are optimized during the calibration process until the relative accuracy is met.
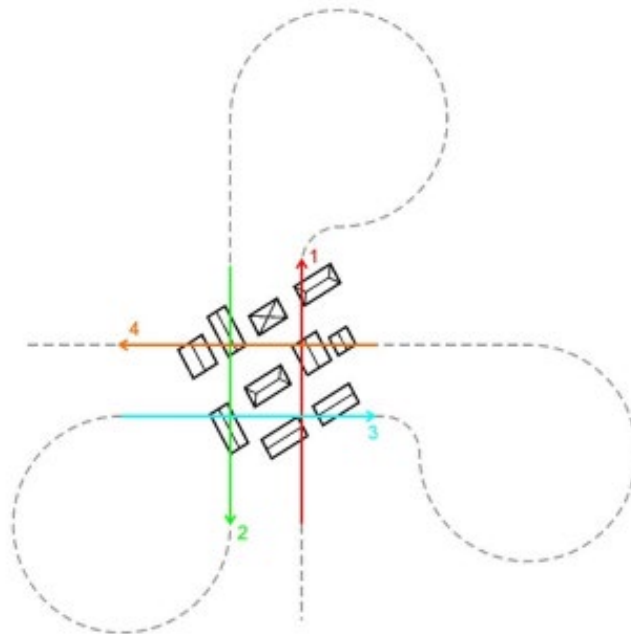

Figure 4. Sbet

2.4 Lidar Acquisition and Processing Details

Table 1 outlines lidar acquisition details, including the project spatial reference system, and processing software used for this project.

Table 1. Lidar acquisition details

Parameter	Value
Number of Flight lines	170
Approximate Area	2,882 sq. miles
Acquisition Dates	December 7, 2019-November 19, 2020
Horizontal Datum	North American Datum of 1983 (NAD83)
Vertical Datum	North American Vertical Datum of 1988 (NAVD88)
Geoid Model	Geoid18
Coordinate Reference System	UTM Zone 15N
Horizontal Units	Meters
Vertical Units	Meters
Kinematic Solution Processing Software:	Applanix Pospac
Point Cloud Generation Software	Riegl RiProcess
Calibration Software	BayesMap StripAlign

2.5 Lidar System parameters

Leading Edge Geomatics operated 3 Cessna 206 Aircrafts throughout the course of the project (Tail # C-FXSS, C-GPTG and C-FRBV) as well as a Piper Aztec (Tail # N105CH) outfitted with RIEGL VQ-1560i lidar system during data collection. Table 2 details the lidar system parameters used during acquisition for this project.

Table 2. Leading Edge Geomatics lidar system parameters.

Parameter	Value
System	VQ-1560i
Altitude (m above ground level)	1800
Nominal flight speed (kts)	130
Scanner pulse rate (kHz)	500
Scan frequency (Hz)	90
Pulse duration of the scanner (ns)	3
Pulse width of the scanner (m)	0.899

Central wavelength of the sensor laser (nm)	1064
Multiple pulses in the air	Yes
Beam divergence (mrad)	</= 0.25
Swath width (m)	1982
Nominal swath width on the ground (m)	1995
Swath overlap (%)	20
Total sensor scan angle (degrees)	58
Computed down track spacing per beam (m)	0.48
Computed cross track Spacing per beam (m)	0.48
Nominal pulse spacing (NPS) (single swath) (m)	0.5
Nominal Pulse Density (NPD) (single swath) (points per sq m)	4
Aggregate NPS (m) (if NPS was designed to be met through single coverage, ANPS and NPS will be equal)	0.5
Aggregate NPD (m) (if NPD was designed to be met through single coverage, ANPD and NPD will be equal)	4
Maximum Number of Returns per Pulse	15

2.6 Acquisition Static Control

Leading Edge Geomatics deployed static GPS base stations during the acquisition of the Eastern Iowa Lidar Project. Locations were chosen based on ease of access and clear line of sight to the satellite constellation. Location data was recorded at a frequency of 1 Hz to ensure the highest quality positional solution. Static base station data was incorporated during the kinematic post-processing of aircraft position.

Base stations were set on existing monuments where available. If no existing monuments were convenient for base station setup, new benchmarks were established. The coordinates of these base stations are provided in the table below.

Table 3. Base stations used to control lidar acquisition.

Name	NAD83(2011) UTM Zone 15N, m		NAD83(2011), m
	Easting (X)	Northing (Y)	Ellipsoid Height
IAAN	644142.237	4662749.624	228.089
IABF	549833.554	4509979.494	236.359
IACI	615701.845	4618575.754	222.251
IADA	697442.450	4609194.119	201.682
IADU	691267.114	4703020.267	216.966

IADY	655217.574	4706872.333	268.051
IAFA	587554.173	4537228.878	208.859
IAFL	584336.066	4539855.710	206.9633
IAGY	517761.270	4690102.198	285.934
IAHO	617904.475	4515650.419	192.761
IAIN	591813.284	4699698.052	272.029
IAKA	609030.705	4593602.828	177.93
IAKY	565985.769	4649458.569	243.208
IAME	660007.333	4587827.182	184.2194
IAMQ	694812.554	4660638.963	188.631
IAMR	625500.439	4704705.861	269.046
IAMS	652613.977	4550148.670	190.921
IAMW	507471.641	4650780.560	274.488
IANW	585461.681	4646031.829	245.271
IARY	591364.297	4691600.121	248.621
IASA	731706.785	4662829.610	160.717
IASG	565956.460	4577591.328	213.439
IATA	537171.305	4646223.372	248.366
IAWA	550073.585	4701934.817	240.868
IAWI	630583.197	4553210.542	192.8638
ILCA	659825.894	4474264.645	166.9916
ILFU	736217.571	4636958.796	155.149
ILGA	720939.766	4535747.380	215.5724
ILMO	715463.149	4594902.572	190.9182

MOCN	624042.745	4444703.621	159.418
MOED	570223.327	4448791.353	194.67
MOKI	535390.129	4458724.831	267.4275
MONY	567570.717	4429582.138	228.582
MOPY	627054.722	4400279.494	166.2583
NLIB	618447.039	4625397.307	208.678
WLNC	687034.323	4745330.037	281.891

2.7 ABGNSS-Inertial Processing

ABGNSS-Inertial processing was performed using the software identified in Table 1. The reference frame used for this processing does not always match the project spatial reference system and is shown in Table 4.

Appendix A contains additional mission GPS and IMU processing covering:

- Pospac graphics and processing
- Graphics of any reference stations used for differential correction
- Graphics of processing interface to show trajectory data and labeled reference stations for each lift (only graphics of trajectory when precise point position is used).
- Graphics of processed plots for each mission/flight/lift to include:
    1. Forward/reverse separation of trajectory
    2. Estimated accuracy of trajectory
    3. Any additional plots used in the analyses of trajectory quality

Table 4. Spatial reference system used for ABGNSS-Inertial processing

Parameter	Value
Horizontal Datum	North American Datum of 1983 (NAD83)
Vertical Datum	North American Vertical Datum of 1988 (NAVD88)
Geoid Model	Geoid18
Coordinate Reference System	UTM Zone 15N
Horizontal Units	Meters

Vertical Units	Meters

2.8   Calibration Process

Lidar mission flight trajectories were combined with raw point files in Riegl RiProcess. The initial points (.las) for each mission calibration were inspected for flight line errors, spatial distribution, data voids, density, or issues with the lidar sensor. If a calibration error greater than specification was observed within the mission, the necessary roll, pitch, and scanner scale corrections were calculated, and corrections were applied to each individual swath using the BayesMap StripAlign software. In addition, all GPS, aircraft trajectory, mission information, and ground control files were reviewed and logged into a database. The missions with the new calibration values were regenerated and validated internally once again to ensure quality.

2.9   Final Calibration Verification

Dewberry surveyed 150 ground control points (GCPs) in flat, non-vegetated areas to test the accuracy of the calibrated swath data. GCPs were located in open, non-vegetated terrain. To assess the accuracy of calibration, the heights of the ground control points were compared with a surface derived from the calibrated swath lidar. A full list of GCPs used for accuracy testing is included in the GCP Survey Report provided with project deliverables.

Table 5. Summary of calibrated swath vertical accuracy tested with ground control points.

Land Cover Type	# of Points	$RMSE_z$ (m)	NVA (m)	Mean (m)	Median (m)	Skew	Std Dev (m)	Min (m)	Max (m)	Kurtosis
Ground Control Points (GCPs)	150	0.06	0.11	0.03	0.04	0.50	0.04	-0.05	0.19	0.78

3. LIDAR ACQUISITION REPORT – AERIAL SERVICES, INC.

Dewberry elected to subcontract the lidar acquisition and calibration activities to Aerial Services, Inc. Aerial Services, Inc. was responsible for providing lidar acquisition and delivery of lidar data files to Dewberry. Dewberry competed the calibration for the Aerial Services Inc acquisition area.

The lidar aerial acquisition for this WUID was conducted between December 7, 2019 to November 19, 2020.

3.1   Acquisition Extents
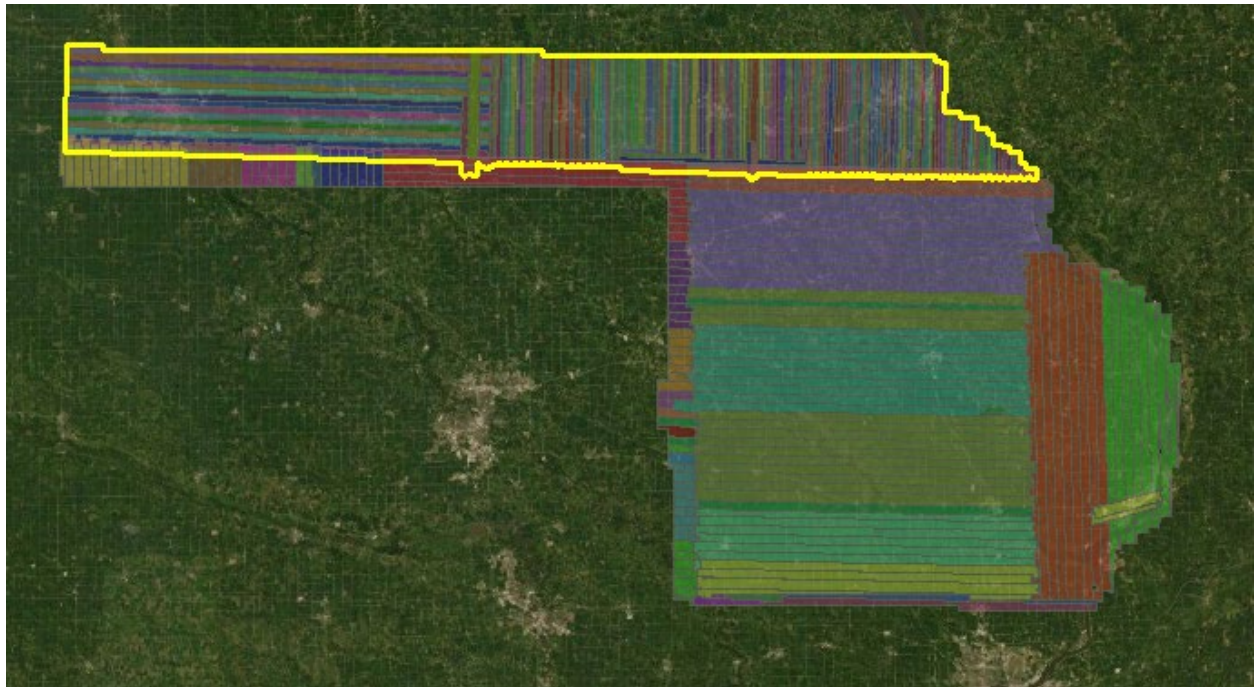
Figure 5 shows flightline vectors by lift.

Figure 5. WUID 300007 ASI swaths

3.2 Acquisition Summary

The Mississippi River runs along the eastern edge of the city of Maquoketa and Dubuque, Iowa as well as the surrounding area. Acquisition of the QL2 lidar within this region of the project was hampered by multiple delays. Dewberry worked closely with its subcontractors, the USGS and its partners to monitor ground conditions and acquire data during optimal windows that met with all project requirements. Acquisition was to begin in the spring of 2019 but was halted due to snow on ground followed by Mississippi River flooding in May 2019 and increasing leaf-on conditions. Dewberry was permitted to restart acquisition in the fall of 2019 but was again hampered by poor ground conditions brought on by an unseasonably wet and warm fall resulting in a longer leaf-on period. Acquisition resumed in December of 2019 for a brief period before COVID-19 restrictions went into effect nationwide and added to further delays as all stakeholders began to follow and enact state and federal guidelines surrounding the pandemic. Dewberry completed acquisition for this project in November of 2020, after communicating with USGS and local stakeholders on how best to proceed given the environmental conditions. The result of these varying delays, coupled with flooding events along the Mississippi River, have resulted in multiple temporal issues along adjoining swaths for this area of the project. Seasonal changes in the water levels, in addition to the localized flooding in some areas, required extra care and effort to determine the true banks of rivers and streams within this area. A "temporal" polygons shapefile is provided that identifies the areas affected by these temporal changes with this WUID delivery. Areas with low ground density and poor ground definition due to flooding, mostly along the banks of the Mississippi River, are delineated in a "low confidence" polygon shapefile.

3.3 Sensor Calibration and Boresight

The initial points for each mission calibration are inspected for flight line errors, flight line overlap, slivers, or gaps in the data, point data minimums, or issues with the lidar unit or GPS. Roll, pitch, and scanner scale are optimized during the calibration process until the relative accuracy is met.

Relative accuracy and internal quality are checked using at least 3 regularly spaced QC blocks in which points from all lines are loaded and inspected. Vertical differences between ground surfaces of each line are displayed. Color scale is adjusted so that errors greater than the specifications are flagged. Cross sections are visually inspected across each block to validate point to point, flight line to flight line and mission to mission agreement.

For this project the specifications used are as follow:

Relative accuracy <= 6 cm maximum differences within individual swaths and <=8 cm RMSDz between adjacent and overlapping swaths.
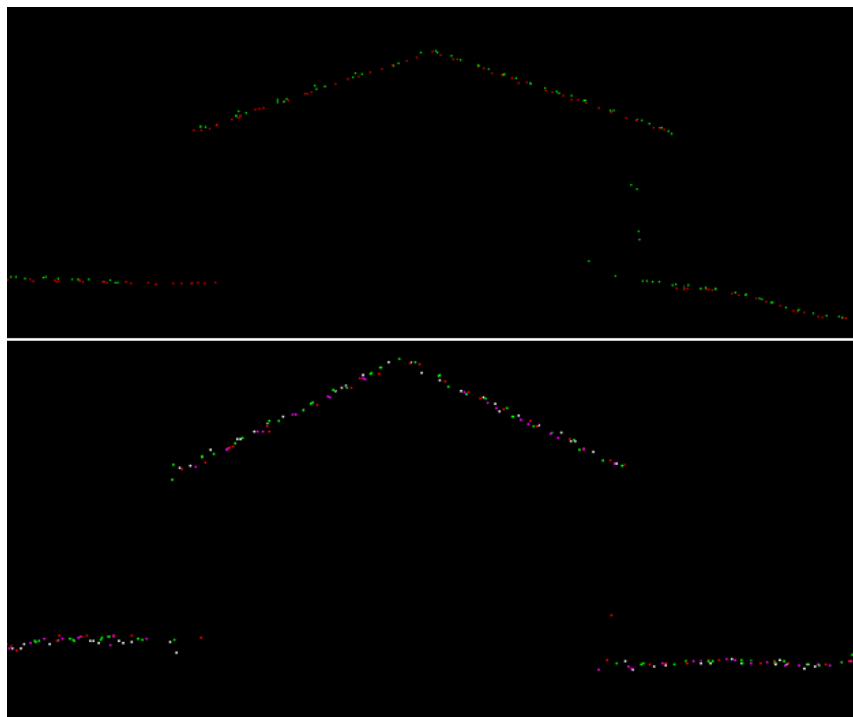

Figure 6. Profile views showing correct roll and pitch adjustments
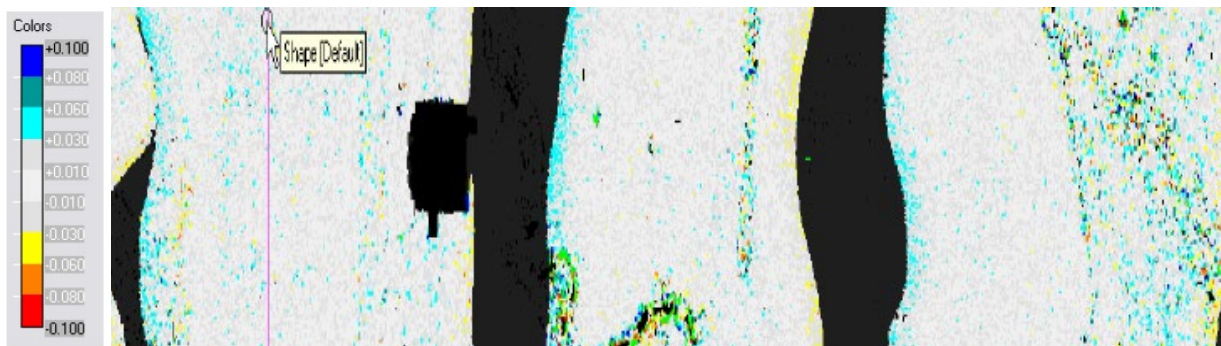
Figure 7. QC block colored by distance to ensure accuracy at swath edges

A different set of QC blocks are generated for final review after all transformations have been applied.

3.4   Lidar Acquisition and Processing Details

ASI planned 194 passes for the Northeastern portion of the project area as a series of parallel flight lines with cross flightlines for the purposes of quality control. The flight plan included zigzag flight line collection as a result of the inherent IMU drift associated with all IMU systems. In order to reduce any margin for error in the flight plan, ASI followed FEMA's Appendix A "guidelines" for flight planning and, at a minimum, includes the following criteria:

- A digital flight line layout using either LEICA MISSION PRO flight design software for the ALS70_HP or TRACKAIR SNAPPLAN flight design software for the Riegl LMSQ-1560 for direct integration into the aircraft flight navigation system.

- Planned flight lines; flight line numbers; and coverage area.

- Lidar coverage extended by a predetermined margin beyond all project borders to ensure necessary over-edge coverage appropriate for specific task order deliverables.

- Local restrictions related to air space and any controlled areas have been investigated so that required permissions can be obtained in a timely manner with respect to schedule. Additionally, ASI will file our flight plans as required by local Air Traffic Control (ATC) prior to each mission.

ASI monitored weather and atmospheric conditions and conducted lidar missions only when no conditions exist below the sensor that will affect the collection of data. These conditions include leaf-off for hardwoods, no snow, rain, fog, smoke, mist and low clouds. Lidar systems are active sensors, not requiring light, thus missions may be conducted during night hours when weather restrictions do not prevent collection. ASI accesses reliable weather sites and indicators (webcams) to establish the highest probability for successful collection in order to position our sensor to maximize successful data acquisition.

Within 72-hours prior to the planned day(s) of acquisition, ASI closely monitored the weather, checking all sources for forecasts at least twice daily. As soon as weather conditions were conducive to acquisition, our aircraft mobilized to the project site to begin data collection. Once on site, the acquisition team took responsibility for weather analysis.

Aerial Services, Inc. lidar sensors are calibrated at designated sites located in Waverly and Hudson, IA and they are periodically checked and adjusted to minimize corrections at project sites.

3.5   Lidar System parameters

Aerial Services, Inc. operated 1 Piper Navajo (Tail # N144AS) outfitted with a RIEGL LMS-Q1560 lidar system and 1 Cessna T206H (Tail # N78AS) outfitted with an ALS70-HP lidar system during data collection. Table 6 and 7 detail the lidar system parameters used during acquisition for this project.

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Table 6. Aerial Services, Inc. lidar system parameters.

Parameter	Value
System	LMS-Q1560
Altitude (m above ground level)	1274
Nominal flight speed (kts)	150
Scanner pulse rate (kHz)	400
Scan frequency (Hz)	107
Pulse duration of the scanner (ns)	3
Pulse width of the scanner (m)	0.9
Central wavelength of the sensor laser (nm)	1064
Multiple pulses in the air	Yes
Beam divergence (mrad)	</= 0.25
Swath width (m)	1428
Nominal swath width on the ground (m)	1428
Swath overlap (%)	30
Total sensor scan angle (degrees)	58.52
Computed down track spacing per beam (m)	0.7
Computed cross track Spacing per beam (m)	0.3
Nominal pulse spacing (NPS) (single swath) (m)	0.45
Nominal Pulse Density (NPD) (single swath) (points per sq m)	4.8
Aggregate NPS (m) (if NPS was designed to be met through single coverage, ANPS and NPS will be equal)	0.45
Aggregate NPD (m) (if NPD was designed to be met through single coverage, ANPD and NPD will be equal)	4.8
Maximum Number of Returns per Pulse	unlimited

Table 7. Aerial Services, Inc. lidar system parameters.

Parameter	Value
System	ALS-70HP
Altitude (m above ground level)	1200
Nominal flight speed (kts)	125
Scanner pulse rate (kHz)	424
Scan frequency (Hz)	47
Pulse duration of the scanner (ns)	9
Pulse width of the scanner (m)	2.7
Central wavelength of the sensor laser (nm)	1064
Multiple pulses in the air	Yes
Beam divergence (mrad)	</= 0.22
Swath width (m)	1119
Nominal swath width on the ground (m)	1119

Swath overlap (%)	30
Total sensor scan angle (degrees)	50
Computed down track spacing per beam (m)	0.53
Computed cross track Spacing per beam (m)	0.72
Nominal pulse spacing (NPS) (single swath) (m)	0.41
Nominal Pulse Density (NPD) (single swath) (points per sq m)	5.9
Aggregate NPS (m) (if NPS was designed to be met through single coverage, ANPS and NPS will be equal)	0.41
Aggregate NPD (m) (if NPD was designed to be met through single coverage, ANPD and NPD will be equal)	5.9
Maximum Number of Returns per Pulse	unlimited

3.6   Acquisition Static Control

ASI utilized the NOAA Continuously Operating Reference Stations (CORS) network (NCN) during the kinematic post-processing of aircraft position for the northeastern Iowa project area. The coordinates of these base stations are provided in the table below.

Table 8. Base stations used to control lidar acquisition.

Name	NAD83(2011) UTM Zone 15N, m		NAD83(2011), m
	Easting (X)	Northing (Y)	Ellipsoid Height
IADE	594821.293	4791578.744	317.531
IAEL	633814.957	4748558.353	300.023
IAMN	620132.103	4654159.238	229.964
IATA	537171.309	4646223.370	248.375
IAAL	517409.504	4732747.645	292.123
IANA	638195.509	4817435.107	173.268
NLIB	618447.038	4625397.312	208.654
WINL	729744.891	4858177.654	244.653
MNSV	541581.870	4861175.592	362.216
MNEY	563754.785	4867251.020	371.911

MNPS	590100.988	4818605.318	381.921
MNCA	621303.869	4832205.238	340.625
WLNC	687034.323	4745330.037	281.891
MNWN	603101.014	4879898.172	179.658
IAHT	470101.880	4792417.862	345.485
JFWS	724621.078	4754968.430	294.677

3.7 ABGNSS-Inertial Processing

Airborne GPS data was processed from the Leica ALS-70 HP scanner using Applanix PosPac 8.2 software, and airborne GPS data for the Riegl LMS-Q1560 scanner was processed with RiProcess. Flights were flown with a minimum of 6 satellites in view (13° above the horizon) and with a PDOP of better than 3. Distances from base station to aircraft were kept to a maximum of 80 km.

For all flights, the GPS data can be classified as excellent, with GPS residuals of 3 cm average or better but no larger than 10 cm being recorded.

GPS processing reports for each mission are included in Appendix B.

3.8   Calibration Process

The initial step of calibration is to verify availability and status of all needed GPS and Laser data against field notes and compile any data if not complete.

Subsequently Leica ALS-70 HP mission points are output using CloudPro, and Riegl LMS-Q1560 mission points are output using RiProcess. The initial point generation for each mission calibration is verified within Microstation/Terrascan for calibration errors. If a calibration error greater than specification is observed within the mission, the roll, pitch and scanner scale corrections that need to be applied are calculated. The missions with the new calibration values are regenerated and validated internally once again to ensure quality.

Data collected by the lidar unit is reviewed for completeness, acceptable density and to make sure all data is captured without errors or corrupted values. In addition, all GPS, aircraft trajectory, mission information, and ground control files are reviewed and logged into a database.

On a project level, a supplementary coverage check is carried out to ensure no data voids unreported by Field Operations are present.

3.9   Final Calibration Verification

Dewberry surveyed 150 ground control points (GCPs) in flat, non-vegetated areas to test the accuracy of the calibrated swath data. GCPs were located in open, non-vegetated terrain. To assess the accuracy of calibration, the heights of the ground control points were compared with a surface derived from the calibrated swath lidar. A full list of GCPs used for accuracy testing is included in the GCP Survey Report provided with project deliverables.

Table 9. Summary of calibrated swath vertical accuracy tested with ground control points.

Land Cover Type	# of Points	RMSE$_z$ (m)	NVA (m)	Mean (m)	Median (m)	Skew	Std Dev (m)	Min (m)	Max (m)	Kurtosis
Ground Control Points (GCPs)	150	0.06	0.11	0.03	0.04	0.50	0.04	-0.05	0.19	0.78

4. LIDAR PRODUCTION & QUALITATIVE ASSESSMENT

4.1   Initial Processing

Following receipt of the calibrated swath data from the acquisition provider, Dewberry performed vertical accuracy validation of the swath data, inter-swath relative accuracy validation, intra-swath relative accuracy validation, verification of horizontal alignment between swaths, and confirmation of point density and spatial distribution. This initial assessment allowed Dewberry to determine whether the data was suitable for full-scale production.

4.1.1   Post Calibration Lidar Review

The table below identifies requirements verified by Dewberry prior to tiling the swath data, running initial ground macros, and starting manual classification.

Table 10. Post calibration and initial processing data verification steps.

Requirement	Description of Deliverables	Additional Comments
Non-vegetated vertical accuracy (NVA) of the swath data meet required specifications of 19.6 cm at the 95% confidence level based on RMSEz (10 cm) x 1.96	The swath NVA was tested and passed specifications.	None
The NPD/NPS (or Aggregate NPD/Aggregate NPS) meets required specification of 2 ppsm or 0.7 m NPS. The NPD (ANPD) is calculated from first return points only.	The average calculated (A)NPD of this project is 5.6 ppsm. Density raster visualization also passed specifications.	None
Spatial Distribution requires 90% of the project grid, calculated with cell sizes of 2*NPS, to contain at least one lidar point. This is calculated from first return points only.	98% of cells (2*NPS cell size) had at least 1 lidar point within the cell.	None
Within swath (Intra-swath or hard surface repeatability) relative accuracy must meet ≤ 6 cm maximum difference	Within swath relative accuracy passed specification.	None
Between swath (Inter-swath or swath overlap) relative accuracy must meet 8 cm RMSDz/16 cm maximum difference. These thresholds are tested in open, flat terrain.	Between swath relative accuracy passed specification, calculated from single return lidar points.	None
Horizontal Calibration-There should not be horizontal offsets (or vertical offsets) between overlapping swaths that would negatively impact the accuracy of the data or the overall usability of the data. Assessments made on rooftops or other hard planar surfaces where available.	Horizontal calibration met project requirements.	None
Ground Penetration-The missions were planned appropriately to meet project density requirements and achieve as much ground penetration beneath vegetation as possible	Ground penetration beneath vegetation was acceptable.	None
Sensor Anomalies-The sensor should perform as expected without anomalies that negatively impact the usability of the data, including issues such as excessive sensor noise and intensity gain or range-walk issues	No sensor anomalies were present.	None
Edge of Flight line bits-These fields must show a minimum value of 0 and	Edge of Flight line bits were populated correctly	None

Requirement	Description of Deliverables	Additional Comments
maximum value of 1 for each swath acquired, regardless of which type of sensor is used		
Scan Direction bits-These fields must show a minimum value of 0 and maximum value of 1 for each swath acquired with sensors using oscillating (back-and-forth) mirror scan mechanism. These fields should show a minimum and maximum of 0 for each swath acquired with Riegl sensors as these sensors use rotating mirrors.	Scan Direction bits were populated correctly	None
Swaths are in LAS v1.4 formatting	Swaths were in LAS v1.4 as required by the project.	None
All swaths must have File Source IDs assigned (these should equal the Point Source ID or the flight line number)	File Source IDs were correctly assigned	None
GPS timestamps must be in Adjusted GPS time format and Global Encoding field must also indicate Adjusted GPS timestamps	GPS timestamps were Adjusted GPS time and Global Encoding field were correctly set to 17	None
Intensity values must be 16-bit, with values ranging between 0-65,535	Intensity values were 16-bit	None
Point Source IDs must be populated and swath Point Source IDs should match the File Source IDs	Point Source IDs were assigned and match the File Source IDs	None

4.2 Data Classification and Editing

Once the calibration, absolute swath vertical accuracy, and relative accuracy of the data were confirmed, Dewberry utilized proprietary and TerraScan software for processing. The acquired 3D laser point clouds were tiled according to the project tile grid using proprietary software. Once tiled, the laser points were classified using a proprietary routine in TerraScan. This routine classified any obvious low outliers in the dataset to class 7 and high outliers in the dataset to class 18. Points along flight line edges that were geometrically unusable were flagged as withheld and classified to a separate class so that they would be excluded from the initial ground algorithm. After points that could negatively affect the ground were removed from class 1, the ground layer was extracted from this remaining point cloud using an iterative surface model.

This surface model was generated using four main parameters: building size, iteration angle, iteration distance, and maximum terrain angle. The initial model was based on low points being selected by a "roaming window" with the assumption that these were the ground points. The size of this roaming window was determined by the building size parameter. The low points were triangulated and the remaining points were evaluated and subsequently added to the model if they met the iteration angle and distance constraints. This process was

repeated until no additional points were added within iterations. Points that did not relate to classified ground within the maximum terrain angle were not captured by the initial model.

After the initial automated ground routine, each tile was imported into TerraScan and a surface model was created to examine the ground classification. Dewberry analysts visually reviewed the ground surface model and corrected errors in the ground classification such as vegetation, buildings, and bridges that were present following the initial processing. Dewberry analysts employed 3D visualization techniques to view the point cloud at multiple angles and in profile to ensure that non-ground points were removed from the ground classification. Bridge decks were classified to class 17 and bridge saddle breaklines were used where necessary. After the ground classification corrections were completed, the dataset was processed through a water classification routine that utilized breaklines to automatically classify hydro features. The water classification routine selected ground points within the breakline polygons and automatically classified them as class 9, water. During this water classification routine, points that were within 1 NPS distance or less of the hydrographic feature boundaries were moved to class 20, ignored ground, to avoid hydro-flattening artifacts along the edges of hydro features.

The withheld bit was set on the withheld points previously identified in TerraScan before the ground classification routine was performed.

After manual classification, the LAS tiles were peer reviewed and then underwent a final independent QA/QC. After the final QA/QC and corrections, all headers, appropriate point data records, and variable length records, including spatial reference information, were updated and verified using proprietary Dewberry software.

4.2.1   Qualitative Review

Dewberry's qualitative assessment of lidar point cloud data utilized a combination of statistical analyses and visual interpretation. Methods and products used in the assessment included profile- and map view-based point cloud review, pseudo image products (e.g., intensity orthoimages), TINs, DEMs, DSMs, and point density rasters. This assessment looked for incorrect classification and other errors sourced in the LAS data. Lidar data are peer reviewed, reviewed by task leads (senior level analysts), and verified by an independent QA/QC team at key points within the lidar workflow.

The following table describes Dewberry's standard editing and review guidelines for specific types of features, land covers, and lidar characteristics.

Table 11. Lidar editing and review guidelines.

Category	Editing Guideline	Additional Comments
No Data Voids	The SOW for the project defines unacceptable data voids as voids greater than 4 x ANPS^2, or 1.96 m^2, that are not related to water bodies or other areas of low near-infrared reflectivity and are not appropriately filled by data from an adjacent swath. The LAS files were used to produce	No unacceptable voids were identified in this dataset

Category	Editing Guideline	Additional Comments
	density grids based on Class 2 (ground) points for review.	
Artifacts	Artifacts in the point cloud are typically caused by misclassification of points in vegetation or man-made structures as ground. Low-lying vegetation and buildings are difficult for automated grounding algorithms to differentiate and often must be manually removed from the ground class. Dewberry identified these features during lidar editing and reclassified them to Class 1 (unassigned). Artifacts up to 0.3 m above the true ground surface may have been left as Class 2 because they do not negatively impact the usability of the dataset.	None
Bridge Saddles	The DEM surface models are created from TINs or terrains. TIN and terrain models create continuous surfaces from the input points, interpolating surfaces beneath bridges where no lidar data was acquired. The surface model in these areas tend to be less detailed. Bridge saddles may be created where the surface interpolates between high and low ground points. Dewberry identifies problems arising from bridge removal and resolves them by reclassifying misclassified ground points to class 1 and/or adding bridge saddle breaklines where applicable due to interpolation.	None
Culverts and Bridges	It is Dewberry's standard operating procedure to leave culverts in the bare earth surface model and remove bridges from the model. In instances where it is difficult to determine whether the feature was a culvert or bridge, Dewberry errs on the side of culverts, especially if the feature is on a secondary or tertiary road.	None
In-Ground Structures	In-ground structures typically occur on military bases and at facilities	No in-ground structures present in this dataset

Category	Editing Guideline	Additional Comments
	designed for munitions testing and storage. When present, Dewberry identifies these structures in the project and includes them in the ground classification.	
Dirt Mounds	Irregularities in the natural ground, including dirt piles and boulders, are common and may be misinterpreted as artifacts that should be removed. To verify their inclusion in the ground class, Dewberry checked the features for any points above or below the surface that might indicate vegetation or lidar penetration and reviews ancillary layers in these locations as well. Whenever determined to be natural or ground features, Dewberry edits the features to class 2 (ground)	No dirt mounds or other irregularities in the natural ground were present in this dataset
Wetland/Marsh Areas	Vegetated areas within wetlands/marsh areas are not considered water bodies and are not hydroflattened in the final DEMs. However, it is sometimes difficult to determine true ground in low wet areas due to low reflectivity. In these areas, the lowest points available are used to represent ground, resulting in a sparse and variable ground surface. Open water within wetland/marsh areas greater than or equal to 2 acres is collected as a waterbody.	No marshes present in the data
Flight Line Ridges	Flight line ridges occur when there is a difference in elevation between adjacent flight lines or swaths. If ridges are visible in the final DEMs, Dewberry ensures that any ridges remaining after editing and QA/QC are within project relative accuracy specifications.	No flight line ridges are present in the data
Temporal Changes	If temporal differences are present in the dataset, the offsets are identified with a shapefile.	Temporal offsets are present in the data due to flooding events and are identified with a shapefile
Low NIR Reflectivity	Some materials, such as asphalt, tars, and other petroleum-based products,	No Low NIR Reflectivity is present in the data

Category	Editing Guideline	Additional Comments
	have low NIR reflectivity. Large-scale applications of these products, including roadways and roofing, may have diminished to absent lidar returns. USGS LBS allow for this characteristic of lidar but if low NIR reflectivity is causing voids in the final bare earth surface, these locations are identified with a shapefile.	
Laser Shadowing	Shadows in the LAS can be caused when solid features like trees or buildings obstruct the lidar pulse, preventing data collection on one or more sides of these features. First return data is typically collected on the side of the feature facing toward the incident angle of transmission (toward the sensor), while the opposite side is not collected because the feature itself blocks the incoming laser pulses. Laser shadowing typically occurs in areas of single swath coverage because data is only collected from one direction. It can be more pronounced at the outer edges of the single coverage area where higher scanning angles correspond to more area obstructed by features. Building shadow in particular can be more pronounced in urban areas where structures are taller. Data are edited to the fullest extent possible within the point cloud. As long as data meet other project requirements (density, spatial distribution, etc.), no additional action taken.	No Laser Shadowing is present in the data

4.2.2   Formatting Review

After the final QA/QC was performed and all corrections were applied to the dataset, all lidar files were updated to the final format requirements and the final formatting, header information, point data records, and variable length records were verified using proprietary tools. The table below lists the primary lidar header fields that are updated and verified.

Table 12. Classified lidar formatting parameters

Parameter	Project Specification	Pass/Fail
LAS Version	1.4	Pass
Point Data Record Format	6	Pass
Horizontal Coordinate Reference System	NAD83 (2011) UTM Zone 15N, meters in WKT format	Pass
Vertical Coordinate Reference System	NAVD88 (Geoid 18), meters in WKT format	Pass
Global Encoder Bit	17 for adjusted GPS time	Pass
Time Stamp	Adjusted GPS time (unique timestamps)	Pass
System ID	Sensor used to acquire data	Pass
Multiple Returns	The sensor shall be able to collect multiple returns per pulse and the return numbers are recorded	Pass
Intensity	16-bit intensity values recorded for each pulse	Pass
Classification	Class 1: Unclassified Class 2: Ground Class 7: Low Noise Class 9: Water Class 17: Bridge Decks Class 18: High Noise Class 20: Ignored Ground	Pass
Withheld Points	Withheld bits set: Class 1 withheld set in overlapping flightlines, and all class 7 & 18 set as withheld	Pass
Scan Angle	Recorded for each pulse	Pass
XYZ Coordinates	Recorded for each pulse	Pass

4.2.3 Synthetic Points

Time of flight laser measurements have their maximum unambiguous range restricted by the maximum distance the laser can travel round-trip before the next laser pulse is emitted. One solution to this problem is to limit "valid" returns to a certain window between specified elevations, or a "range gate"; however, this technique can prevent some returns from being captured if there is terrain outside of the range gate. It can also cause some late returns to be georeferenced as part subsequent pulses.

The multiple time around (MTA) capabilities of Riegl sensors enable the recording of lidar returns any distance from the laser (within detection capabilities) without forcing range gate restrictions. However, there is still a possibility that a late return will occur simultaneously with a pulse emission. The backscatter energy from the laser optics and the atmosphere directly below the aircraft during this event can effectively blind the sensor, making it unable to discern information about the laser return. Because this occurs more consistently with later returns, this blind zone is typically found in a narrow band along the edges of the sensor's range. The result is a predictable geometry of voids (typically within project specifications) in the point cloud.

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During post-processing of the lidar data, Riegl software interpolates coordinates within the blind zones between last returns on each side of the gap. These are flagged as "synthetic" points and are assigned a valid time stamp, though they do not have any waveform data or pulse width information. Amplitude and reflectance are averaged from surrounding points. The assignment of synthetic points does not change the original raw point cloud data.

This dataset contains flagged synthetic points. The images below show an example from a different dataset of synthetic points applied to the ground class of the lidar point cloud.
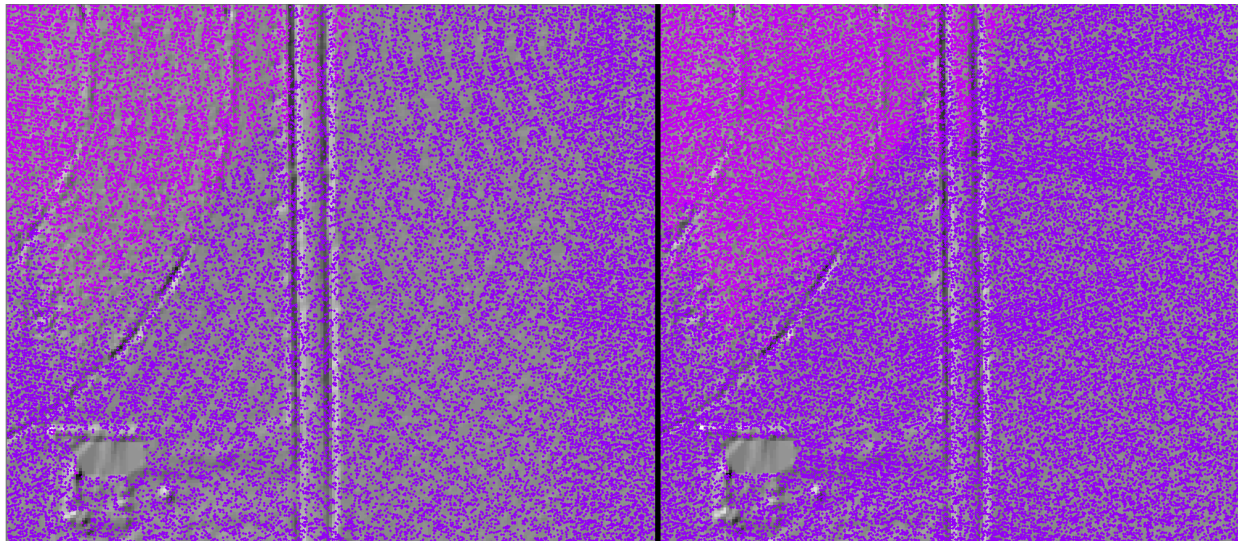

Figure 8. The left image shows ground classified without synthetic points. The right image shows ground classified with synthetic points. Both images are overlaid on a hillshade of the example area.

5. BREAKLINE PRODUCTION & QUALITATIVE ASSESSMENT

5.1 Breakline Production Methodology

Breaklines were manually digitized within an Esri software environment, using full point cloud intensity imagery, bare earth terrains and DEMs, the lidar point cloud, and ancillary ortho imagery where appropriate.

When data characteristics are suitable, Dewberry may use eCognition software to generate initial, automated water polygons, which are then manually reviewed and refined where necessary.

Breakline features with static or semi-static elevations (ponds and lakes, bridge saddles, and soft feature breaklines) were converted to 3D breaklines within the Esri environment where breaklines were draped on terrains or the las point cloud. Subsequent processing was done on ponds/lakes to identify the minimum z-values within these features and re-applied that minimum elevation to all vertices of the breakline feature.

Linear hydrographic features show downhill flow and maintain monotonicity. These breaklines underwent conflation by using a combination of Esri and LP360 software. Centerlines were draped on terrains, enforced for monotonicity, and those elevations were then assigned to the bank lines for the final river/stream z-values.

Tidal breaklines may have been converted to 3D using either method, dependent on the variables within each dataset.

5.1.1   Breakline Collection Requirements

The table below outlines breakline collection requirements for this dataset.

Table 13. Breakline collection requirements

Parameter	Project Specification	Additional Comments
Ponds and Lakes	Breaklines are collected in all inland ponds and lakes ~2 acres or greater. These features are flat and level water bodies at a single elevation for each vertex along the bank.	None
Rivers and Streams	Breaklines are collected for all streams and rivers ~100' nominal width or wider. These features are flat and level bank to bank, gradient will follow the surrounding terrain and the water surface will be at or below the surrounding terrain. Streams/river channels will break at culvert locations however not at elevated bridge locations.	None
Tidal	Breaklines are collected as polygon features depicting water bodies such as oceans, seas, gulfs, bays, inlets, salt marshes, very large lakes, etc. Includes any significant water body that is affected by tidal variations. Tidal variations over the course of collection, and between different collections, can result in discontinuities along shorelines. This is considered normal and should be retained. Variations in water surface elevation resulting from tidal variations during collection should not be removed or adjusted. Features should be captured as a dual line with one line on each bank. Each vertex placed shall maintain vertical integrity. Parallel points on opposite banks of the tidal waters must be captured at the same elevation to ensure flatness of the water feature. The entire water	No tidally influenced features are in this dataset so no tidal breaklines were collected.

	surface edge is at or below the immediate surrounding terrain.	
Islands	Donuts will exist where there are islands greater than 1 acre in size within a hydro feature.	None
Bridge Saddle Breaklines	Bridge Saddle Breaklines are collected where bridge abutments were interpolated after bridge removal causing saddle artifacts.	None
Soft Features	Soft Feature Breaklines are collected where additional enforcement of the modeled bare earth terrain was required, typically on hydrographic control structures or vertical waterfalls, due to large vertical elevation differences within a short linear distance on a hydrographic features.	Soft Features were collected in this dataset to aid in breakline enforcement in certain areas.

5.2   Breakline Qualitative Assessment

Dewberry performed both manual and automated checks on the collected breaklines. Breaklines underwent peer reviews, breakline lead reviews (senior level analysts), and final reviews by an independent QA/QC team. The table below outlines high level steps verified for every breakline dataset.

Table 14. Breakline verification steps.

Parameter	Requirement	Pass/Fail
Collection	Collect breaklines according to project specifications using lidar-derived data, including intensity imagery, bare earth ground models, density models, slope models, and terrains.	Pass
Placement	Place the breakline inside or seaward of the shoreline by 1-2 x NPS in areas of heavy vegetation or where the exact shoreline is hard to delineate.	Pass
Completeness	Perform a completeness check, breakline variance check, and all automated checks on each block before designating that block complete.	Pass
Merged Dataset	Merge completed production blocks. Ensure correct horizontal and vertical snapping between all production blocks. Confirm correct horizontal placement of breaklines.	Pass
Merged Dataset Completeness Check	Check entire dataset for features that were not captured but that meet baseline specifications or	Pass

	other metrics for capture. Features should be collected consistently across tile boundaries.	
Edge Match	Ensure breaklines are correctly edge-matched to adjoining datasets. Check completion type, attribute coding, and horizontal placement.	Pass
Vertical Consistency	Waterbodies shall maintain a constant elevation at all vertices Vertices should not have excessive min or max z-values when compared to adjacent vertices Intersecting features should maintain connectivity in X, Y, Z planes Dual line streams shall have the same elevation at any given cross-section of the stream	Pass
Vertical Variance	Using a terrain created from lidar ground (class 2, 8, and 20 as applicable) and water points (class 9) to compare breakline Z values to interpolated lidar elevations to ensure there are no unacceptable discrepancies.	Pass
Monotonicity	Dual line streams generally maintain a consistent down-hill flow and collected in the direction of flow – some natural exceptions are allowed	Pass
Topology	Features must not overlap or have gaps Features must not have unnecessary dangles or boundaries	Pass
Hydro-classification	The water classification routine selected ground points within the breakline polygons and automatically classified them as class 9, water. During this water classification routine, points that were within 1 NPS distance or less of the hydrographic feature boundaries were moved to class 20, ignored ground, to avoid hydroflattening artifacts along the edges of hydro features.	Pass
Hydro-flattening	Perform hydro-flattening and hydro-enforcement checks. Tidal waters should preserve as much ground as possible and can be non-monotonic.	Pass

6. DEM PRODUCTION & QUALITATIVE ASSESSMENT

6.1 DEM Production Methodology

Dewberry utilized LP360 to generate DEM products and both ArcGIS and Global Mapper for QA/QC.

The final classified lidar points in all bare earth classes were loaded into LP360 along with the final 3D breaklines and the project tile grid. A raster was generated from the lidar data with breaklines enforced and clipped to the project tile grid. The DEM was reviewed for any issues requiring corrections, including remaining lidar misclassifications, erroneous breakline elevations, incorrect or incomplete hydro-flattening or hydro-enforcement, and processing artifacts. The formatting of the DEM tiles was verified before the tiles were loaded into Global Mapper to ensure that there was no missing or corrupt data and that the DEMs matched seamlessly across tile boundaries. A final qualitative review was then conducted by an independent review department within Dewberry.

6.2 DEM Qualitative Assessment

Dewberry performed a comprehensive qualitative assessment of the bare earth DEM deliverables to ensure that all tiled DEM products were delivered with the proper extents, were free of processing artifacts, and contained the proper referencing information. Dewberry conducted the review in ArcGIS using a hillshade model of the full dataset with a partially transparent colorized elevation model overlaid. The tiled DEMs were reviewed at a scale of 1:5,000 to look for artifacts caused by the DEM generation process and to verify correct and complete hydro-flattening and hydro-enforcement. Upon correction of any outstanding issues, the DEM data was loaded into Global Mapper for its second review and to verify corrections.

The table below outlines high level steps verified for every DEM dataset.

Table 15. DEM verification steps.

Parameter	Requirement	Pass/Fail
Digital Elevation Model (DEM) of bare-earth w/ breaklines	DEM of bare-earth terrain surface (1 meter) is created from lidar ground points and breaklines. DEMs are tiled without overlaps or gaps, show no edge artifact or mismatch, DEM deliverables are .tif format	Pass
DEM Compression	DEMs are not compressed	Pass
DEM NoData	Areas outside survey boundary are coded as NoData. Internal voids (e.g., open water areas) are coded as NoData (-999999)	Pass
Hydro-flattening	Ensure DEMs were hydro-flattened or hydro-enforced as required by project specifications	Pass
Monotonicity	Verify monotonicity of all linear hydrographic features	Pass
Breakline Elevations	Ensure adherence of breaklines to bare-earth surface elevations, i.e., no floating or digging hydrographic feature	Pass
Bridge Removal	Verify removal of bridges from bare-earth DEMs and no saddles present	Pass
DEM Artifacts	Correct any issues in the lidar classification that were visually	Pass

	expressed in the DEMs. Reprocess the DEMs following lidar corrections.	
DEM Tiles	Split the DEMs into tiles according to the project tiling scheme	Pass
DEM Formatting	Verify all properties of the tiled DEMs, including coordinate reference system information, cell size, cell extents, and that compression is not applied to the tiled DEMs	Pass
DEM Extents	Load all tiled DEMs into Global Mapper and verify complete coverage within the (buffered) project boundary and verify that no tiles are corrupt	Pass

7. DERIVATIVE LIDAR PRODUCTS

USGS required several derivative lidar products to be created. Each type of derived product is described below.

7.1 Swath Separation Images

Swath separation images representing interswath alignment have been delivered. These images were created from the last return of all points except points classified as noise or flagged as withheld. The images are in .TIFF format. The swath separation images are symbolized by the following ranges:

- 0-8 cm: **Green**
- 8-16 cm: **Yellow**
- >16: **Red**

7.2 Interswath and Intraswath Polygons

7.2.1 Interswath Accuracy

The Interswath accuracy, or overlap consistency, measures the variation in the lidar data within the swath overlap. Interswath accuracy measures the quality of the calibration or boresight adjustment of the data in each lift. Per USGS specifications, overlap consistency was assessed at multiple locations within overlap in minimally sloped (<10 degrees), non-vegetated areas of only single returns. As with precision, the interswath consistency was reported by way of a polygon shapefile delineating the sample areas checked and attributed with the following by using all cells whose pixel center is contained within each polygon as sample values:

- Minimum difference in the sample area (numeric)
- Maximum difference in the sample area (numeric)
- RMSDz (Root Mean Square Difference in the vertical/z direction) of the sample area (numeric). Intraswath Accuracy

7.2.2 Intraswath Accuracy

The intraswath accuracy, or the precision of lidar, measures variations on a surface expected to be flat and without variation. Precision is evaluated to confirm that the lidar system is performing properly and without gross internal error that may not be otherwise apparent. To measure the precision of a lidar dataset, level or flat surfaces were assessed. Swath data were assessed using only first returns in non-vegetated areas.

Precision was reported by way of a polygon shapefile delineating the sample areas checked and attributed with the following and using the cells within each polygon as sample values:

- Minimum slope-corrected range (numeric)
- Maximum slope-corrected range (numeric)
- RMSDz of the slope-corrected range (numeric).