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38184 Sycan
LIDAR PROCESSING REPORT

Project ID: 221827
Work Unit: 300184

2023

Prepared for:

USGS
science for a changing world

Prepared by:

N|V|5
GEOSPATIAL

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Appendix A: Flight Logs

1. Summary / Scope

1.1. Summary

This report contains a summary of the 38184 Sycan, Work Unit 300184 lidar acquisition task order, issued by USGS under their Contract G16PC00016 on August 2, 2021. The task order yielded a work unit area covering 182 square miles over Oregon. This was collected at Quality Level 1. The intent of this document is only to provide specific validation information for the data acquisition/collection, processing, and production of deliverables completed as specified in the task order.

1.2. Scope

Aerial topographic lidar was acquired using state of the art technology along with the necessary surveyed ground control points (GCPs) and airborne GPS and inertial navigation systems. The aerial data collection was designed with the following specifications listed in Table 1 below.

Table 1. Originally Planned Lidar Specifications

Average Point Density	Flight Altitude (AGL)	Field of View	Minimum Side Overlap	RMSEz
0.35 pts / m2	2,083 m	58.5°	20%	≤ 10 cm

1.3. Coverage

The Work Unit boundary covers 182 square miles over Oregon. Project extents are shown in Figure 1.

1.4. Duration

Lidar data was acquired from June 22, 2020 to July 22, 2022 in 10 total lifts. See "Section: 2.4. Time Period" for more details.

1.5. Issues

There were no issues to report.

38184 Sycan Work Unit 300184 Projected Coordinate System: UTM Zone 10N Horizontal Datum: NAD83 (2011) Vertical Datum: NAVD88 (GEOID 18) Units: Meters	
Lidar Point Cloud	Classified Point Cloud in .LAS 1.4 format
Rasters	• 0.5-meter Hydro-flattened Bare Earth Digital Elevation Model (DEM) in GeoTIFF format • 1-meter Intensity images in GeoTIFF format • 1-meter Maximum Surface Height Raster in GeoTIFF format • 1-meter Swath Seperation Images in GeoTIFF format • 1-meter Digital Surface Model (DSM) in GeoTIFF format
Vectors	Shapefiles (*.shp) • Project Boundary • Lidar Tile Index • Calibration and QC Checkpoints (NVA/VVA) • Continuous Hydro-flattened Breaklines Geodatabase (*.gdb) • Flightlines
Reports	Reports in PDF format • Focus on Delivery • Focus on Accuracy • Processing Report
Metadata	XML Files (*.xml) • Breaklines • Classified Point Cloud • DEM • DSM • Intensity Imagery

38184 Sycan
Work Unit 300184 Boundary
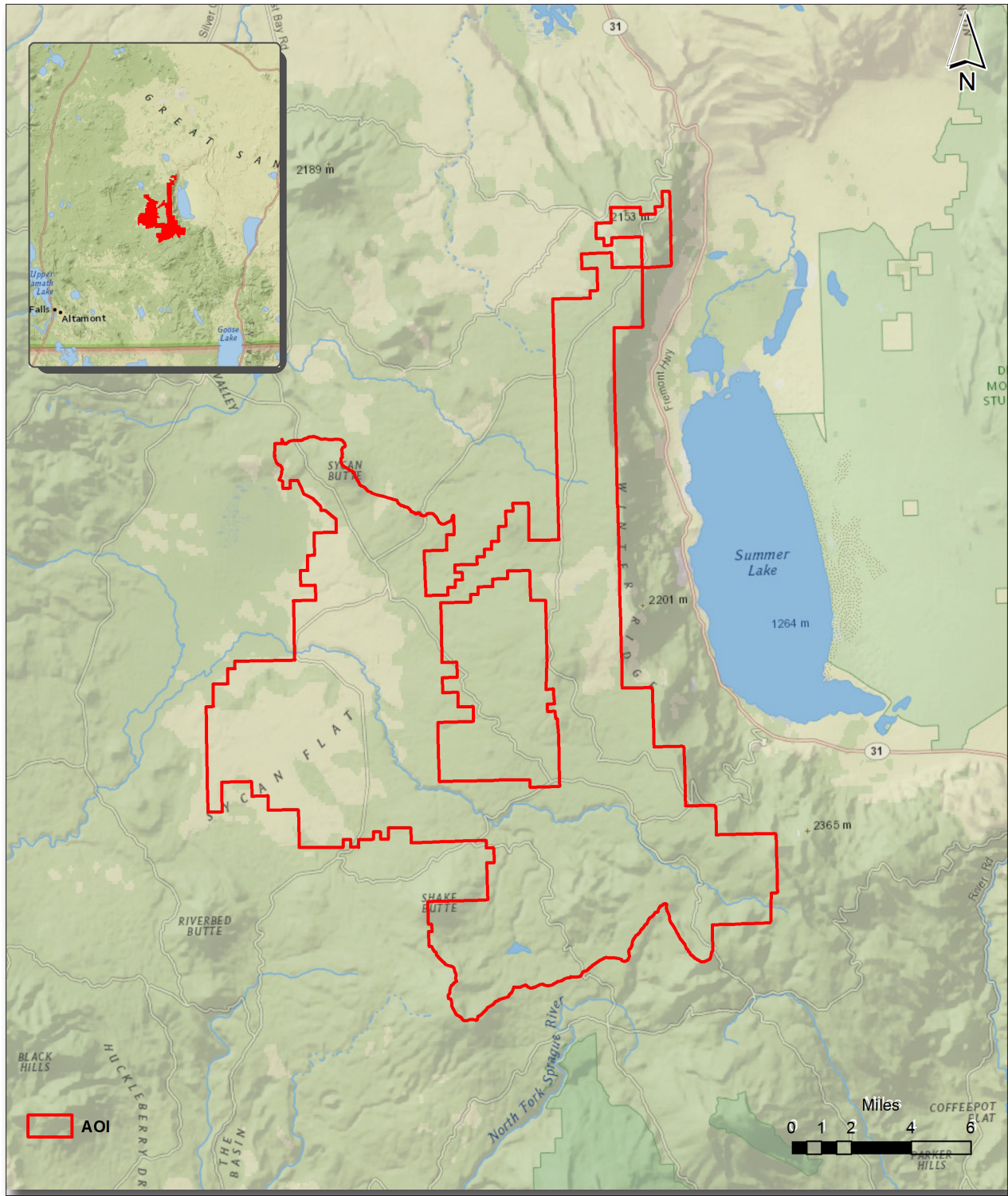
Figure 1. Work Unit Boundary

2. Planning / Equipment

2.1. Flight Planning

Flight planning was based on the unique project requirements and characteristics of the project site. The basis of planning included: required accuracies, type of development, amount / type of vegetation within project area, required data posting, and potential altitude restrictions for flights in project vicinity.

Detailed project flight planning calculations were performed for the project using RiPARAMETERS planning software.

2.2. Lidar Sensor

NV5 Geospatial utilized RieglVQ1560ii lidar sensors (Figure 2), serial number(s) 4046 and 3546, for data acquisition.

The Riegl 1560II system is a dual channel waveform processing airborne scanning system. It has a laser pulse repetition rate of up to 4 MHz resulting in up to 2.66 million measurements per second. The system utilizes a Multi-Pulse in the Air option (MPIA) and an integrated IMU/GNSS unit.

A brief summary of the aerial acquisition parameters for the project are shown in the lidar System Specifications in Table 2.

Table 2. Lidar System Specifications

		RieglVQ1560ii (SN4046)	RieglVQ1560ii (SN3546)
Terrain and Aircraft Scanner	Flying Height	2500 m	2500 m
	Recommended Ground Speed	150 kts	145 kts
Scanner	Field of View	58.5°	58.5°
	Scan Rate Setting Used	2 x 76.5 lps	102 x 2 Hz
Laser	Laser Pulse Rate Used	2 x 417 kHz	634 x 2 kHz
	Multi Pulse in Air Mode	yes	yes
Coverage	Full Swath Width	2790 m	7385 m
	Line Spacing	0.951 m	3323 m
Point Spacing and Density	Average Point Spacing	0.35 m	0.35 m
	Average Point Density	8 pts / m^2	8 pts / m^2

Figure 2. RieglVQ1560ii Lidar Sensor

2.3. Aircraft

All flights for the project were accomplished through the use of customized aircraft. Plane type and tail numbers are listed below.

Lidar Collection Planes
- Cessna Caravan (single-turboprop), Tail Number(s): N473TW
- Cessna 206 Stationair (piston-single), Tail Number(s): N223TC

These aircraft provided an ideal, stable aerial base for lidar acquisition. These aerial platforms have relatively fast cruise speeds, which are beneficial for project mobilization / demobilization while maintaining relatively slow stall speeds, proving ideal for collection of high-density, consistent data posting using a state-of-the-art Riegl lidar system. Some of NV5 Geospatial's operating aircraft can be seen in Figure 3 below.

Figure 3. Some of NV5 Geospatial's Aircraft

2.4. Time Period

Project specific flights were conducted between June 22, 2020 to July 22, 2022. Ten aircraft lifts were completed. Accomplished lifts are listed below.

Lift
07202022A_4046_N473TW
07212022A_4046_N473TW
07222022A_4046_N473TW
Coverage_20210925_194724
Coverage_20210927_133927
Coverage_20210928_150128
Coverage_20211008_133706
Coverage_20211011_015113
Coverage_20211013_200324
Coverage_20211020_212148

3. Processing Summary

3.1. Flight Logs

Flight logs were completed by Lidar sensor technicians for each mission during acquisition. These logs depict a variety of information, including:

- Job / Project #
- Flight Date / Lift Number
- FOV (Field of View)
- Scan Rate (HZ)
- Pulse Rate Frequency (Hz)
- Ground Speed
- Altitude
- Base Station
- PDOP avoidance times
- Flight Line #
- Flight Line Start and Stop Times
- Flight Line Altitude (AMSL)
- Heading
- Speed
- Returns
- Crab

Notes: (Visibility, winds, ride, weather, temperature, dew point, pressure, etc). Project specific flight logs for each sortie are available in Appendix A.

3.2. Lidar Processing

Applanix + POSPac software was used for post-processing of airborne GPS and inertial data (IMU), which is critical to the positioning and orientation of the lidar sensor during all flights. Applanix POSPac combines aircraft raw trajectory data with stationary GPS base station data yielding a "Smoothed Best Estimate Trajectory" (SBET) necessary for additional post processing software to develop the resulting geo-referenced point cloud from the lidar missions.

During the sensor trajectory processing (combining GPS & IMU datasets) certain statistical graphs and tables are generated within the Applanix POSPac processing environment which are commonly used as indicators of processing stability and accuracy. This data for analysis include: max horizontal / vertical GPS variance, separation plot, altitude plot, PDOP plot, base station baseline length, processing mode, number of satellite vehicles, and mission trajectory.

Point clouds were created using the RiPROCESS software. The generated point cloud is the mathematical three dimensional composite of all returns from all laser pulses as determined from the aerial mission. The point cloud is imported into GeoCue distributive processing software. Imported data is tiled and then calibrated using TerraMatch and proprietary software. Using TerraScan, the vertical accuracy of the surveyed ground control is tested and any bias is removed from the data. TerraScan and TerraModeler software packages are then used for automated data classification and manual cleanup. The data are manually reviewed and any remaining artifacts removed using functionality provided by TerraScan and TerraModeler.

DEMs and Intensity Images are then generated using proprietary software. In the bare earth surface model, above-ground features are excluded from the data set. Global Mapper is used as a final check of the bare earth dataset.

Finally, proprietary software is used to perform statistical analysis of the LAS files.

Software	Version
Applanix + POSPac	8.6
RiPROCESS	1.8.6
GeoCue	2020.1.22.1
Global Mapper	19.1;20.1
TerraModeler	21.008
TerraScan	21.016
TerraMatch	21.007

3.3. LAS Classification Scheme

The classification classes are determined by Lidar Base Specifications 2020, Rev. A and are an industry standard for the classification of lidar point clouds. All data starts the process as Class 1 (Unclassified), and then through automated classification routines, the classifications are determined using TerraScan macro processing.

The classes used in the dataset are as follows and have the following descriptions:

Table 3. LAS Classifications

	Classification Name	Description
1	Processed, but Unclassified	Laser returns that are not included in the ground class, or any other project classification
2	Bare earth	Laser returns that are determined to be ground using automated and manual cleaning algorithms
7	Low Noise	Laser returns that are often associated with scattering from reflective surfaces, or artificial points below the ground surface
17	Bridge Deck	Laser returns falling on bridge decks
18	High Noise	Laser returns that are often associated with birds or artificial points above the ground surface

3.4. Classified LAS Processing

The bare earth surface is then manually reviewed to ensure correct classification on the Class 2 (Ground) points. After the bare- earth surface is finalized; it is then used to generate all hydro-breaklines through heads-up digitization.

All ground (ASPRS Class 2) lidar data inside of the Lake Pond and Double Line Drain hydro flattening breaklines were then classified to water (ASPRS Class 9) using proprietary tools. A buffer of 1.5 feet/0.5 meter was also used around each hydro flattened feature to classify these ground (ASPRS Class 2) points to Ignored ground (ASPRS Class 20). All Lake Pond Island and Double Line Drain Island features were checked to ensure that the ground (ASPRS Class 2) points were reclassified to the correct classification after the automated classification was completed.

Any noise that was identified either through manual review or automated routines was classified to the appropriate class (ASPRS Class 7 and/or ASPRS Class 18) followed by flagging with the withheld bit.

All data was manually reviewed and any remaining artifacts removed using functionality provided by TerraScan and TerraModeler. Global Mapper is used as a final check of the bare earth dataset. GeoCue was then used to create the deliverable industry-standard LAS files for all point cloud data. NV5 Geospatial's proprietary software was used to perform final statistical analysis of the classes in the LAS files, on a per tile level to verify final classification metrics and full LAS header information.

3.5. Hydro-Flattened Breakline Processing

Using heads-up digitization, all Lake-Ponds, Double Line Drains, and Islands are manually collected that are within the project size specification. This includes Lake-Ponds greater than 2 acres in size, Double Line Drains with greater than a 100 foot nominal width, and Islands greater than 1 acre in size within a collected hydro feature. Lidar intensity imagery and bare-earth surface models are used to ensure appropriate and complete collection of these features.

Elevation values are assigned to all collected hydro features via NV5 Geospatial's proprietary software. This software sets Lake-Ponds to an appropriate, single elevation to allow for the generation of hydro-flattened digital elevation models (DEM). Double Line Drain elevations are assigned based on lidar elevations and surrounding terrain feature to ensure all breaklines match the lidar within acceptable tolerances. Some deviation is expected between breakline and lidar elevations due to monotonicity, connectivity, and flattening rules that are enforced on the breaklines. Once completeness, horizontal placement, and vertical variances are reviewed, all breaklines are evaluated for topological consistency and data integrity using a combination of proprietary tools and manual review of hydro-flattened DEMs.

Breaklines are combined into one seamless shapefile, clipped to the project boundary, and imported into an Esri file geodatabase for delivery.

3.6. Hydro-Flattened Raster DEM Processing

Hydro-Flattened DEMs (topographic) represent a lidar-derived product illustrating the grounded terrain and associated breaklines (as described above) in raster form. NV5 Geospatial's proprietary software was used to take all input sources (bare earth lidar points, bridge and hydro breaklines, etc.) and create a Triangulated Irregular Network (TIN) on a tile-by-tile basis. Data extending past the tile edge is incorporated in this process so that proper triangulation can occur. From the TIN, linear interpolation is used to calculate the cell values for the raster product. The raster product is then clipped back to the tile edge so that no overlapping cells remain across the project area. A 32-bit floating point GeoTIFF DEM was generated for each tile with a pixel size of 0.5-meter. NV5 Geospatial's proprietary software was used to write appropriate horizontal and vertical projection information as well as applicable header values into the file during product generation. Each DEM is reviewed in Global Mapper to check for any surface anomalies and to ensure a seamless dataset. NV5 Geospatial ensures there are no void or no-data values (-999999) in each derived DEM. This is achieved by using propriety software checking all cell values that fall within the project boundary. NV5 Geospatial uses a proprietary tool called FOCUS on Delivery to check all formatting requirements of the DEMs against what is required before final delivery.

3.7. Intensity Image Processing

Intensity images represent reflectivity values collected by the lidar sensor during acquisition. Proprietary software generates intensity images using first returns and excluding those flagged with a withheld bit. Intensity images are linearly scaled to a value range specific to the project area to standardize the images and reduce differences between individual tiles. Appropriate horizontal projection information as well as applicable header values are written during product generation.

3.8. Swath Separation Raster Processing

Swath Separation Images are rasters that represent the interswath alignment between flight lines and provide a qualitative evaluation of the positional quality of the point cloud. NV5 Geospatial proprietary software generated 1-meter raster images in GeoTIFF format using last returns, excluding points flagged with the withheld bit, and using a point-in-cell algorithm. Images are generated with a 75% intensity opacity and (4) absolute 8-cm intervals, see below for interval coloring. Intensity images are linearly scaled to a value range specific to the project area to standardize the images and reduce differences between individual tiles. Appropriate horizontal projection information as well as applicable header values are written to the file during product generation. NV5 Geospatial uses a proprietary tool called FOCUS on Delivery to check all formatting requirements of the images against what is required before final delivery.

🟩	0-8cm
🟨	8-16cm
🟧	16-24cm
🟥	>24cm

3.9. Maximum Surface Height Raster Processing

Maximum Surface Height rasters (topographic) represent a lidar-derived product illustrating natural and built-up features. NV5 Geospatial's proprietary software was used to take all first-return classified lidar points, excluding those flagged with a withheld bit, and create a raster on a tile-by-tile basis. Data extending past the tile edge is incorporated in this process so that proper gridding can occur. The raster product is then clipped back to the tile edge so that no overlapping cells remain across the project area. A 32-bit floating point GeoTIFF was generated for each tile with a pixel size of 1-meter. NV5 Geospatial's proprietary software was used to write appropriate horizontal and vertical projection information as well as applicable header values into the file during product generation. Each maximum surface height raster is reviewed in Global Mapper to check for any anomalies and to ensure a seamless dataset. NV5 Geospatial uses a proprietary tool called FOCUS on Delivery to check all formatting requirements of the DEMs against what is required before final delivery.

3.10. Top of Canopy DSM Processing

First-return highest hit lidar points from the vegetation class were used to create a 0.5 meter raster DSM. Using automated scripting routines within proprietary software, TIF files were created for each tile. Each surface is reviewed using Global Mapper to check for any surface anomalies or incorrect elevations found within the surface.

3.11. Raster DSM Processing

A normalized digital surface model was created by removing the DEM surface from the DSM surface. This allows for the visualization of all features (cars, trees, buildings, etc.) that are above the ground level. Each surface is reviewed using Global Mapper to check for any surface anomalies or incorrect elevations found within the surface.
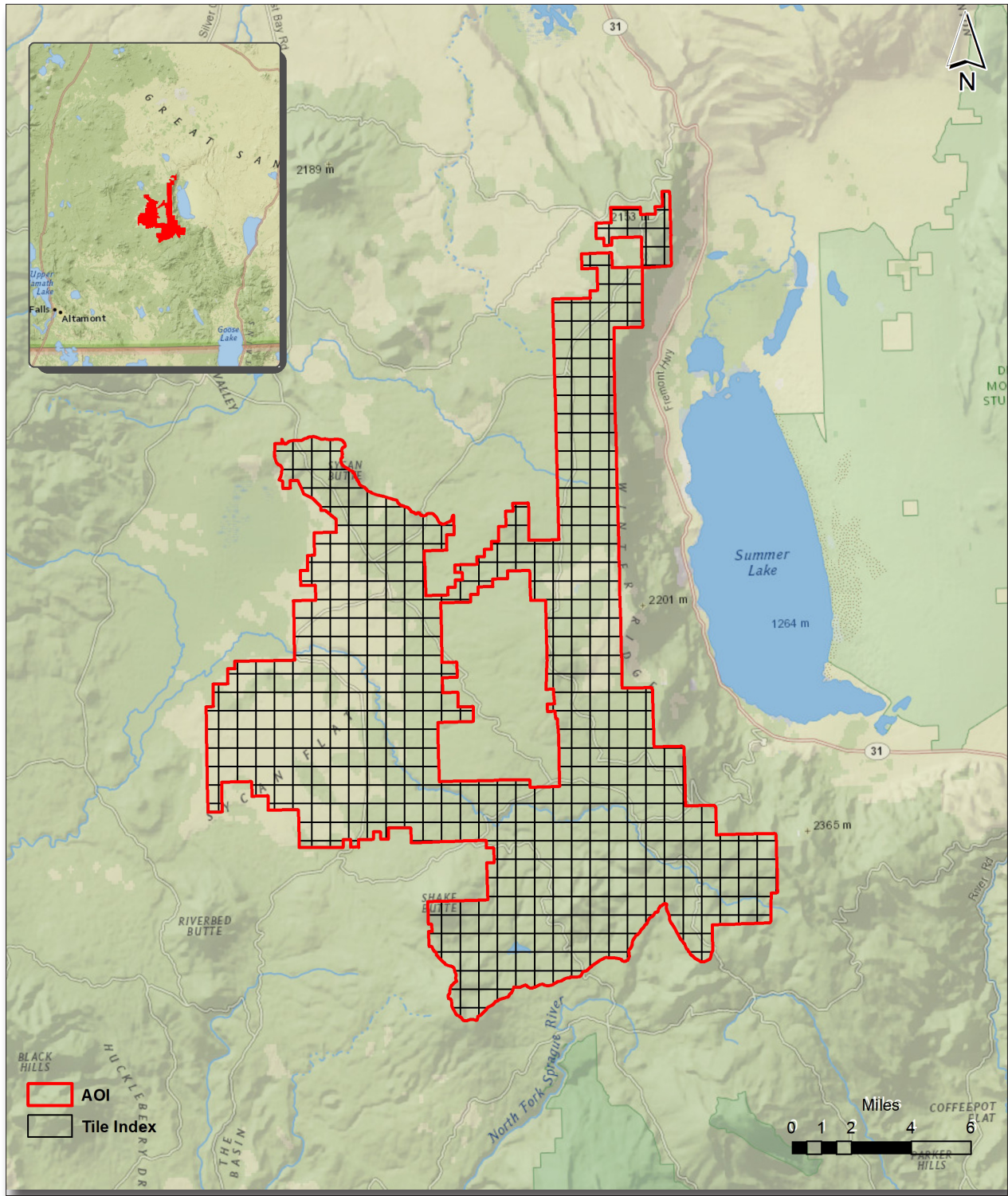
38184 Sycan
Work Unit 300184 Tile Layout

Figure 4. Lidar Tile Layout

4. Project Coverage Verification

A proprietary tool (FOCUS on Flight) produces grid-based polygons of each flightline, depicting exactly where lidar points exist. These swath polygons are reviewed against the project boundary to verify adequate project coverage. Please refer to Figure 5.

38184 Sycan
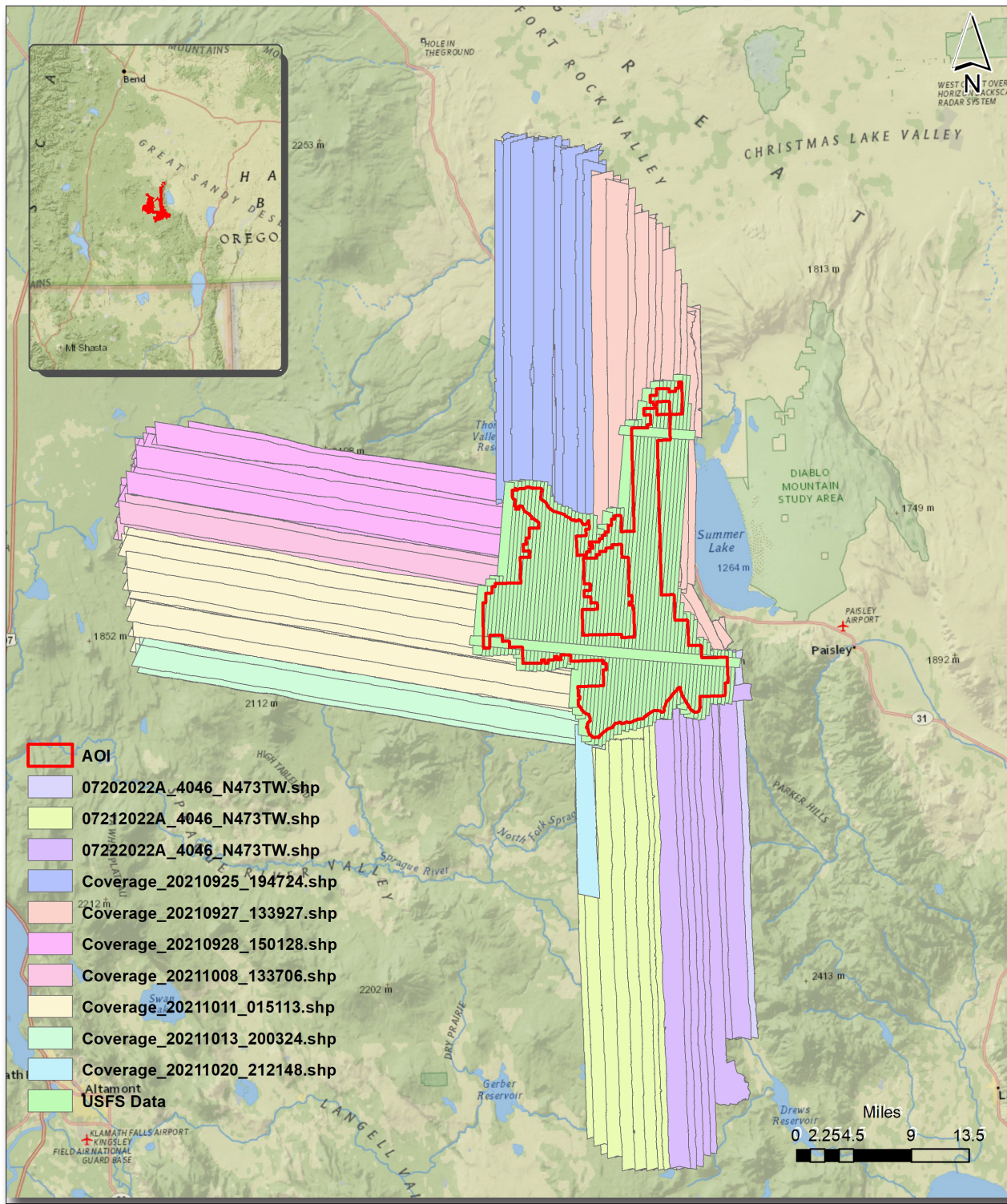# Work Unit 300184 Lidar Coverage

Figure 5. Lidar Coverage

5. Geometric Accuracy

5.1. Horizontal Accuracy

Lidar horizontal accuracy is a function of Global Navigation Satellite System (GNSS) derived positional error, flying altitude, and INS derived attitude error. The obtained $RMSE_r$ value is multiplied by a conversion factor of 1.7308 to yield the horizontal component of the National Standards for Spatial Data Accuracy (NSSDA) reporting standard where a theoretical point will fall within the obtained radius 95% of the time. Based on a flying altitude of 2083 meters, an IMU error of 0.002 decimal degrees, and a GNSS positional error of 0.015 meters, this project was compiled to meet 0.23 meter horizontal accuracy at the 95% confidence level. A summary is shown below.

Horizontal Accuracy	
$RMSE_r$	0.43 ft
	0.13 m
ACC_r	0.75 ft
	0.23 m

5.2. Relative Vertical Accuracy

Relative vertical accuracy refers to the internal consistency of the data set as a whole: the ability to place an object in the same location given multiple flight lines, GPS conditions, and aircraft attitudes. When the lidar system is well calibrated, the swath-to-swath vertical divergence is low (<0.10 meters). The relative vertical accuracy was computed by comparing the ground surface model of each individual flight line with its neighbors in overlapping regions. The average (mean) line to line relative vertical accuracy for the 38184 Sycan project was 0.042 feet (0.013 meters). A summary is shown below.

Relative Vertical Accuracy	
Sample	60 flight line surfaces
Average	0.042 ft
	0.013 m
Median	0.042 ft
	0.013 m
RMSE	0.042 ft
	0.013 m
Standard Deviation (1σ)	0.003 ft
	0.001 m
1.96σ	0.006 ft
	0.002 m

0, 0 Relative Vertical Accuracy (ft)
Total Compared Points (n = 6,059,770,199)
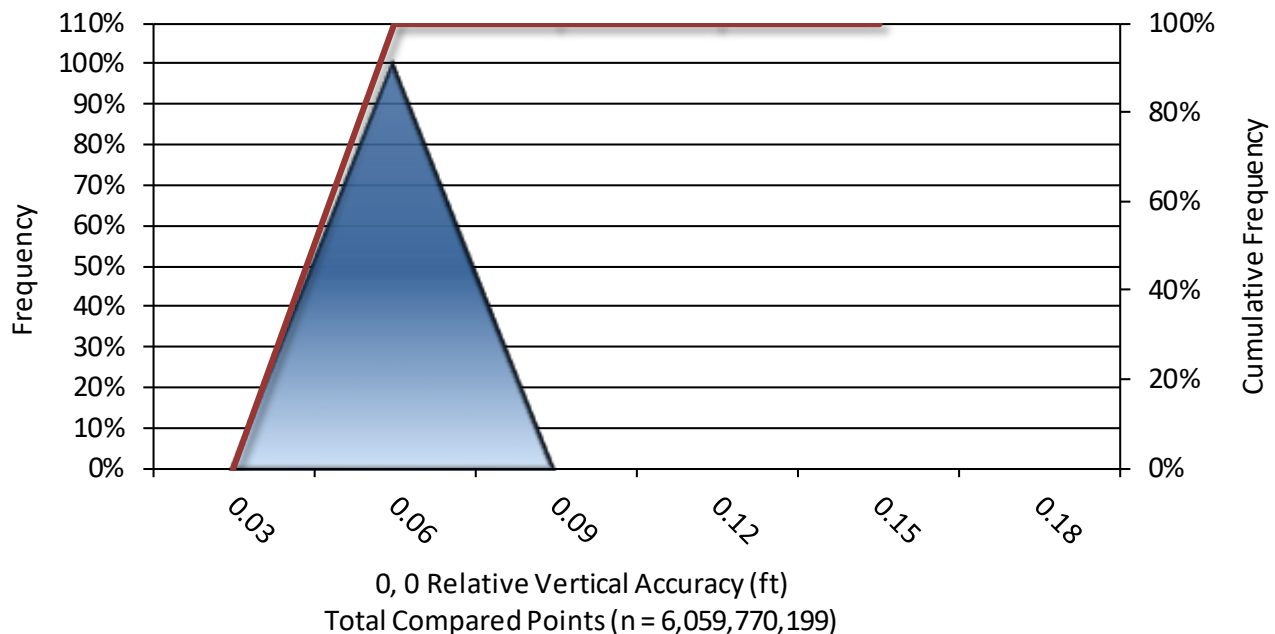
Project Report Appendices

The following section contains the appendices as listed in

the 38184 Sycan Lidar Project Report.

Appendix A

Flight Logs

Appendix B

Survey Report