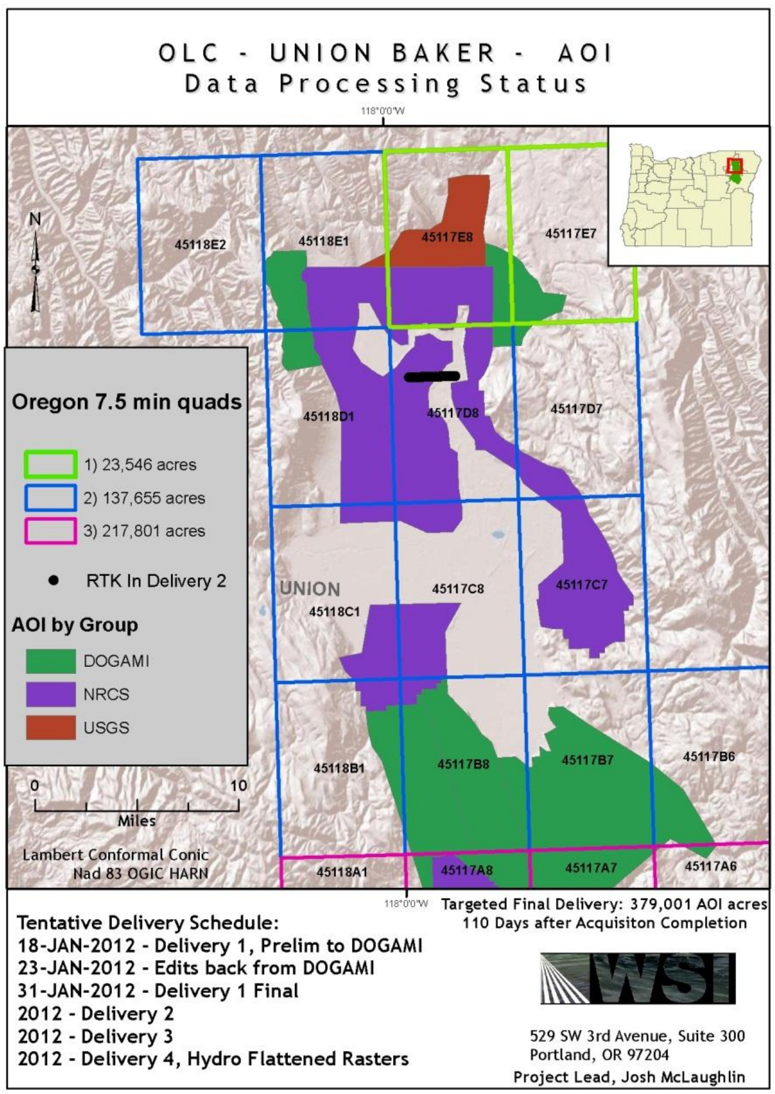
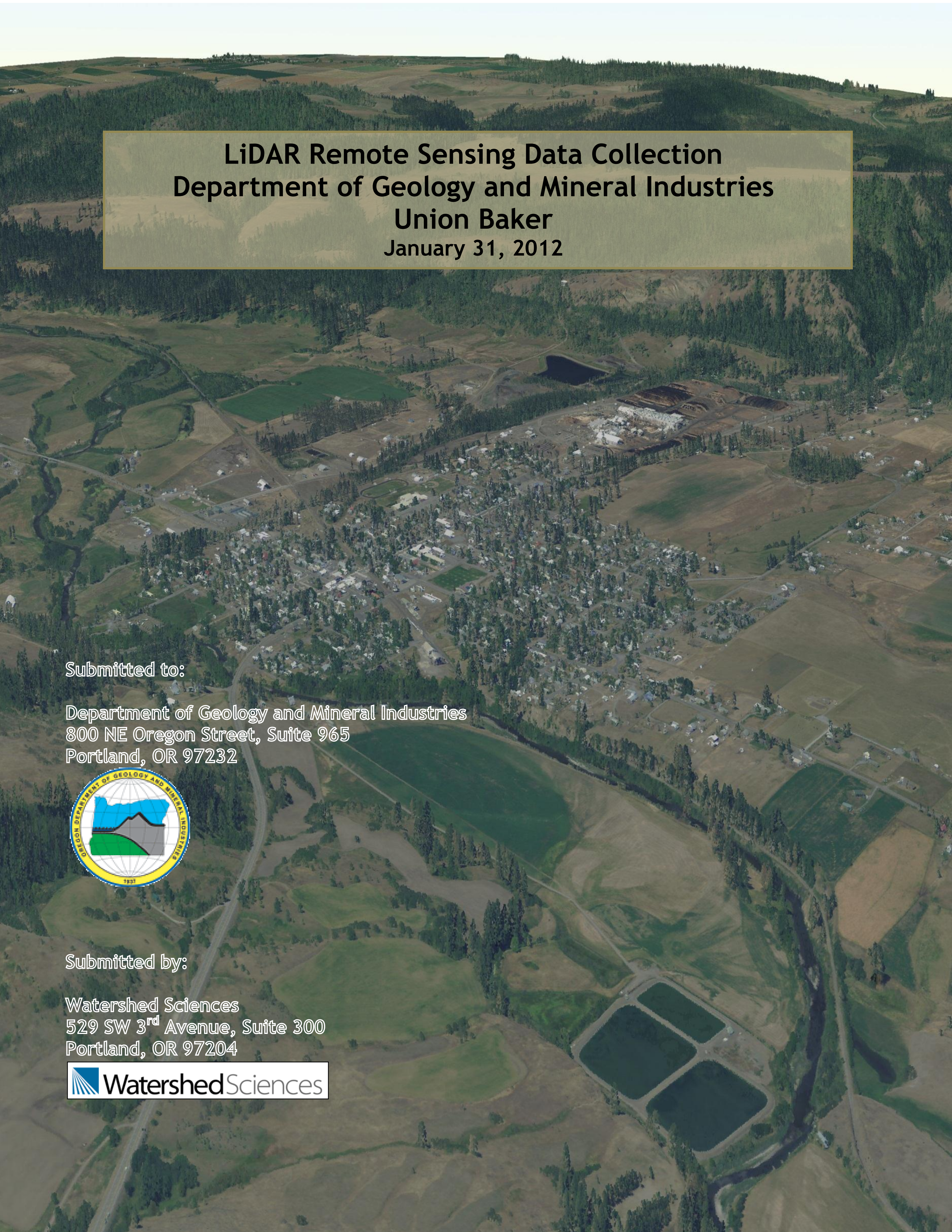
# Union Baker 2011, Explanation of RTK in Delivery 1

In order to expedite the delivery of the Union Baker AOI, Watershed Sciences has divided the project into three separate delivery areas, following acquisition progress to-date. As a result, delivery 1 will not include any RTK in the data report. All RTK collected during that acquisition period occurred South of the 45117E7 and 45117E8.

WSI's RTK collection methodology is robust. 425 RTK checkpoints were aquired along the flight-lines used in calibrating this data. It is purely coincidental that those RTK points do not occur within this delivery delineation. WSI chose to eliminate the reporting of the RTK points solely on the basis that the RTK is not in delivery area 1. Full reporting of absolute accuracy will be included with the delivery 2 data report. The RTK specifically referenced is within quad 45117D8.





# LiDAR Remote Sensing Data Collection
# Department of Geology and Mineral Industries
# Union Baker

**January 31, 2012**

Submitted to:

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# LiDAR Remote Sensing Data Collection:
## DOGAMI, Newberry Study Area

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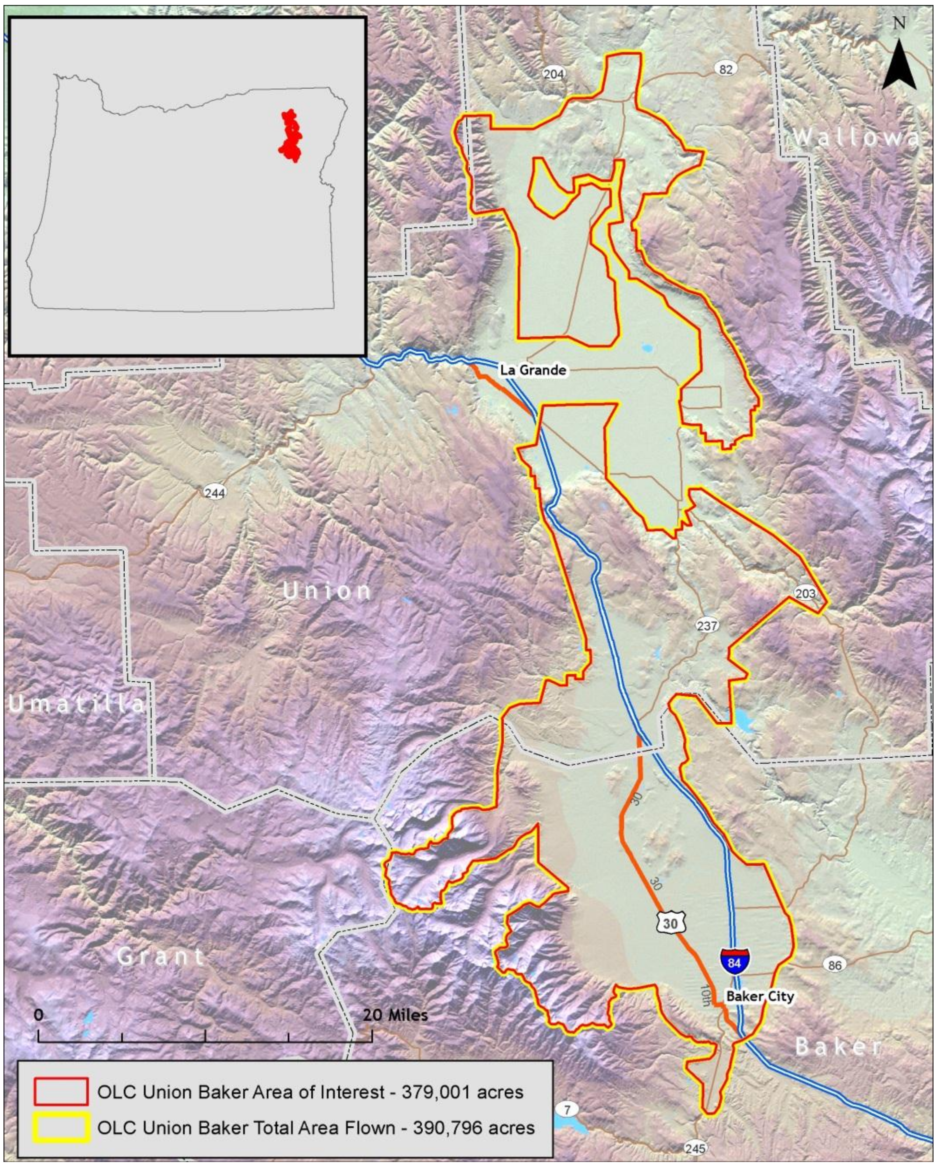
Watershed Sciences

# 1. Overview

## 1.1 Study Area

Watershed Sciences, Inc. is in the process of collecting Light Detection and Ranging (LiDAR) data of the Union Baker Study Area for the Oregon Department of Geology and Mineral Industries (DOGAMI). The area of interest (AOI) totals 592 square miles (379,001 acres) and the total area flown (TAF) covers 611 square miles (390,796 acres). The TAF acreage is greater than the original AOI acreage due to buffering and flight planning optimization (**Figure 1.1** below). This report reflects all data and cumulative statistics for the overall LiDAR survey. DOGAMI data are delivered in OGIC (HARN): Projection: Oregon Statewide Lambert Conformal Conic; horizontal and vertical datum: NAD83 (HARN)/NAVD88 (Geoid03); units: International Feet.

**Figure 1.1.** *DOGAMI Union Baker*

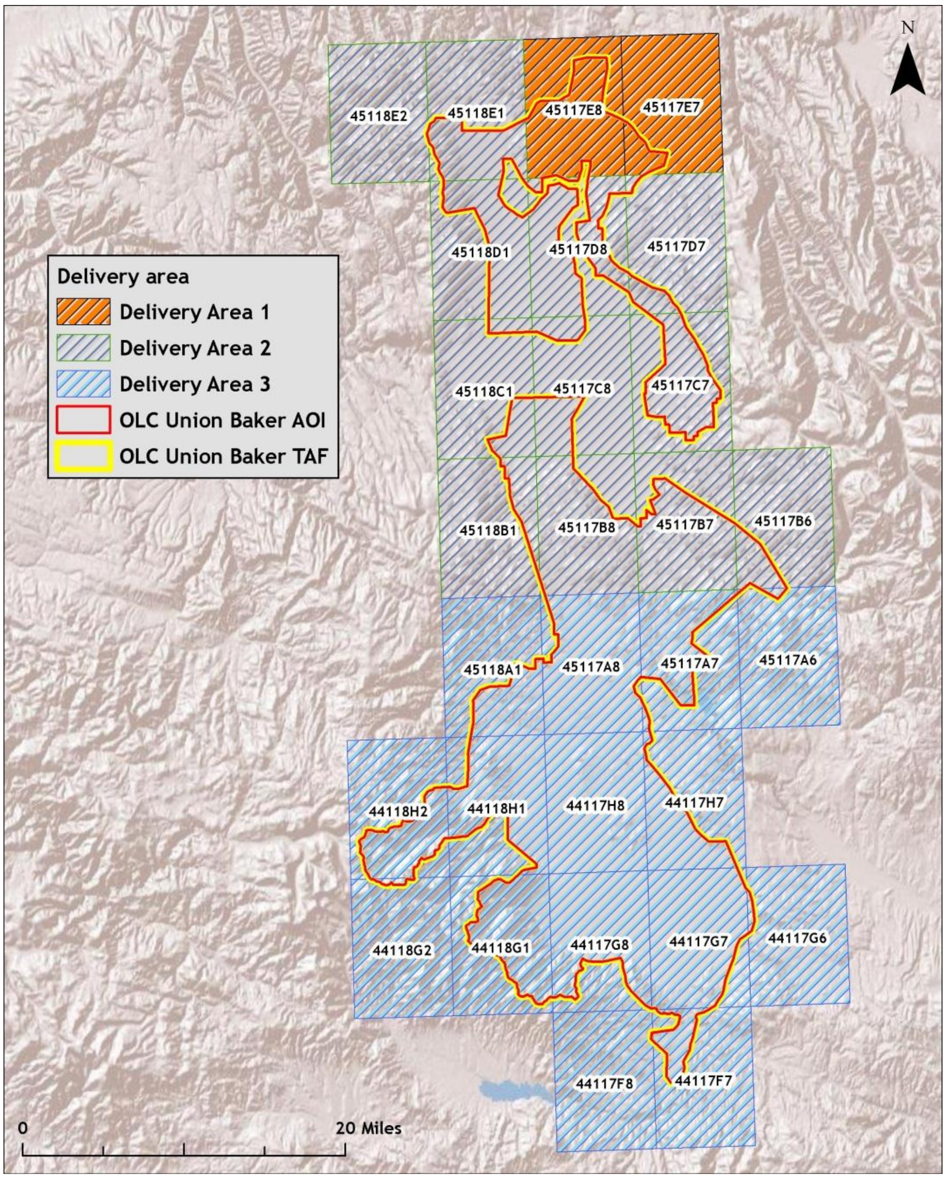


## 1.2 Area Delivered to Date

**Table 1.1.** *Total delivered acreage detailed below.*

| DOGAMI Union Baker Study Area | | | | |
|---|---|---|---|---|
| | **Delivery Date** | **Acquisition Dates** | **AOI Acres** | **TAF Acres** |
| **Delivery Area 1** | January 31, 2011 | December 8, 2011 – December 12, 2011 | **23,546** | **24,422** |

**Figure 1.2.** *Union Baker study Area, illustrating the delivered 7.5 minute USGS quads and delivery areas.*



# 2. Acquisition

## 2.1 Airborne Survey Overview – Instrumentation and Methods

The LiDAR survey utilized the Leica ALS70 and an ALS50 Phase II sensors mounted in a Cessna Caravan 208B and a Partenavia p.68. The Leica systems were set to acquire ≥96,000 and ≥195,000 laser pulses per second (i.e. 190kHz pulse rate) and flown at 900 and 1400 meters above ground level (AGL), capturing a scan angle of ±14° from nadir[1]. These settings are developed to yield points with an average native density of ≥8 points per square meter over terrestrial surfaces. The native pulse density is the number of pulses emitted by the LiDAR system. Some types of surfaces (i.e. dense vegetation or water) may return fewer pulses than the laser originally emitted. Therefore, the delivered density can be less than the native density and lightly variable according to distributions of terrain, land cover and water bodies.

*The Cessna Caravan is a powerful, stable platform, which is ideal for the often remote and mountainous terrain found in the Pacific Northwest. The Leica ALS60 sensor head installed in the Caravan is shown on the right.*

**Table 2.1** *LiDAR Survey Specifications*

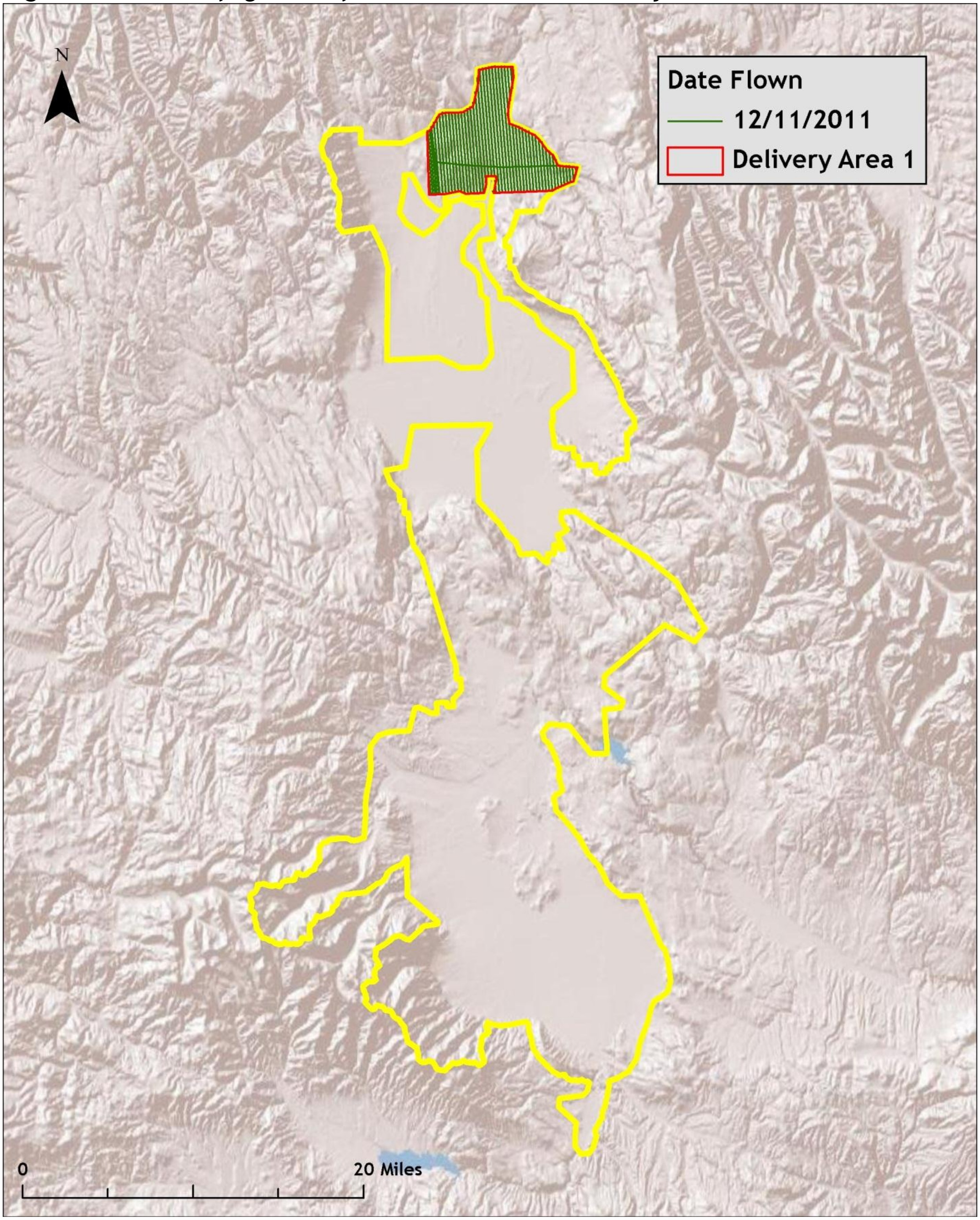
| | |
|---|---|
| Sensors | Leica ALS70 and ALS50 Phase II |
| Survey Altitude (AGL) | 900 m and 1400 m |
| Pulse Rate | >96 kHz and >195KHz |
| Pulse Mode | Single |
| Mirror Scan Rate | 52 Hz |
| Field of View | 30° (±14° from nadir) |
| Roll Compensated | Up to 15° |
| Overlap | 100% (60% Side-lap) |

The study area was surveyed with opposing flight line side-lap of ≥60% (≥100% overlap) to reduce laser shadowing and increase surface laser painting. The system allows up to four range measurements per pulse, and all discernible laser returns were processed for the output dataset.

To solve for laser point position, it is vital to have an accurate description of aircraft position and attitude. Aircraft position is described as x, y and z and measured twice per second (2 Hz) by an onboard differential GPS unit. Aircraft attitude is measured 200 times per second (200 Hz) as pitch, roll and yaw (heading) from an onboard inertial measurement unit (IMU). **Figure 2.1** shows the flight lines completed for current processing.

[1] Nadir refers to the perpendicular vector to the ground directly below the aircraft. Nadir is commonly used to measure the angle from the vector and is referred to a "degrees from nadir".

**Figure 2.1.** *Actual flightlines for the Union Baker Delivery area 1.*



## 2.2 Ground Survey – Instrumentation and Methods

During the LiDAR survey, static (1 Hz recording frequency) ground surveys were conducted over either known or set monuments. Monument coordinates are provided in **Table 2.2** and shown in **Figure 2.2** for the AOI. After the airborne survey, the static GPS data are processed using triangulation with continuous operation stations (CORS) and checked using the Online Positioning User Service (OPUS[2]) to quantify daily variance. Multiple sessions are processed over the same monument to confirm antenna height measurements and reported position accuracy. Control monuments are located within 13 nautical miles of the survey area(s). Indexed by time, these GPS data records are used to correct the continuous onboard measurements of aircraft position recorded throughout the mission.

### 2.2.1 Instrumentation

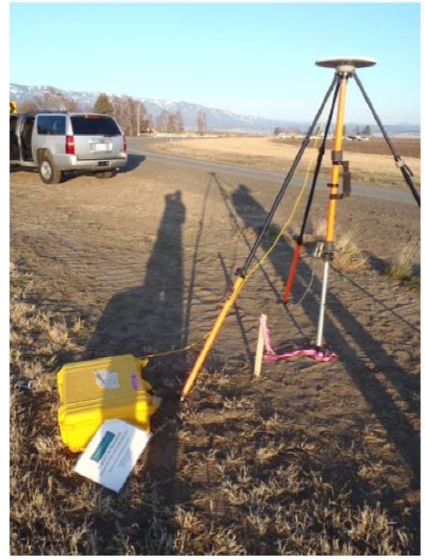
For this study area all Global Navigation Satellite System (GNSS[3]) survey work utilizes a Trimble GPS receiver model R7 with a Zephyr Geodetic antenna with ground plane for static control points. The Trimble GPS R8 unit is used primarily for Real Time Kinematic (RTK) work but can also be used as a static receiver. For RTK data, the collector begins recording after remaining stationary for 5 seconds then calculating the pseudo range position from at least three epochs with the relative error under 1.5 cm horizontal and 2 cm vertical. All GPS measurements are made with dual frequency L1-L2 receivers with carrier-phase correction.

### 2.2.2 Monumentation


Whenever possible, existing and established survey benchmarks shall serve as control points during LiDAR acquisition including those previously set by Watershed Sciences. In addition to NGS, the county surveyor's offices and the Oregon Department of Transportation (ODOT) often establish their own benchmarks. NGS benchmarks are preferred for control points. In the absence of NGS benchmarks, county surveys, or ODOT monumentation, Watershed Sciences produces our own monuments. These monuments are spaced at a minimum of one mile and every effort is made to keep these monuments within the public right of way or on public lands. If monuments are required on private property, consent from the owner is required. All monumentation is done with 5/8" x 30" rebar topped with a 2" diameter aluminum cap stamped "Watershed Sciences, Inc.".

[2] Online Positioning User Service (OPUS) is run by the National Geodetic Survey to process corrected monument positions.
[3] GNSS: Global Navigation Satellite System consisting of the U.S. GPS constellation and Soviet GLONASS constellation

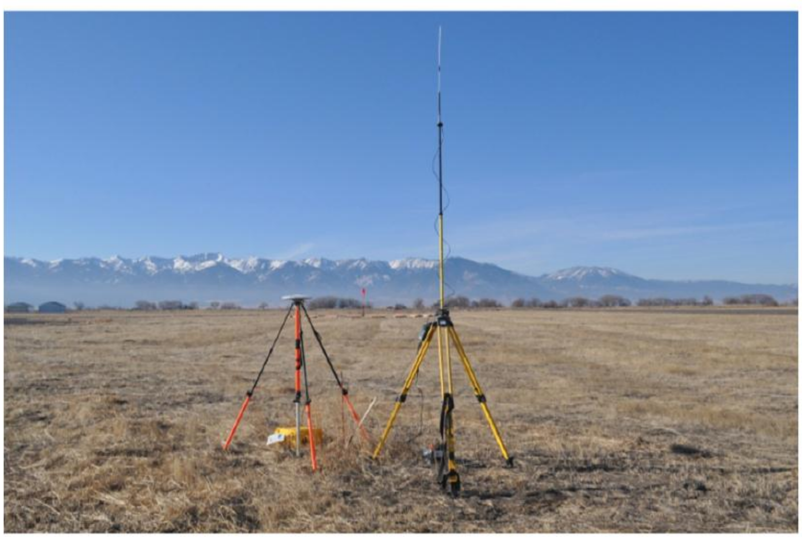
### 2.2.3 Methodology



Each aircraft is assigned a ground crew member with two R7 receivers and an R8 receiver. The ground crew vehicles are equipped with standard field survey supplies and equipment including safety materials. All control points are observed for a minimum of two survey sessions lasting no fewer than 2 hours. At the beginning of every session the tripod and antenna are reset, resulting in two independent instrument heights and data files. Data are collected at a rate of 1Hz using a 10 degree mask on the antenna.

The ground crew uploads the GPS data onto the Dropbox website on a daily basis to be returned to the office for Professional Land Surveyor (PLS) oversight, Quality Assurance/Quality Control (QA/QC) review and processing. OPUS processing triangulates the monument position using 3 CORS stations resulting in a fully adjusted position. CORPSCON[4] 6.0.1 software is used to convert the geodetic positions from the OPUS reports. After multiple days of data have been collected at each monument, accuracy and error ellipses are calculated. This information leads to a rating of the monument based on FGDC-STD-007.2-1998[5] Part 2 table 2.1 at the 95% confidence level.

All RTK measurements were made during periods with a Position Dilution of Precision (PDOP) of ≤ 3.0 and in view of at least six satellites by the stationary reference and roving receiver. RTK positions are collected on 20% of the flight lines and on bare earth locations such as paved, gravel or stable dirt roads, and other locations where the ground is clearly visible (and is likely to remain visible) from the sky during the data acquisition and RTK measurement period(s). In order to facilitate comparisons with LiDAR measurements, RTK measurements are not taken on highly reflective surfaces such as center line stripes or lane markings on roads. RTK points were taken no closer than one meter to any nearby terrain breaks such as road edges or drop offs. In addition, it is desirable to include locations that can be readily identified and occupied during subsequent field visits in support of other quality control procedures described later. Examples of identifiable locations would include manhole and other flat utility structures that have clearly indicated center points or other measurement locations. In the absence of utility structures, a PK nail can be driven into asphalt or concrete and marked with paint.



Multiple differential GPS units were used in the ground based real-time kinematic (RTK) portion of the survey. To collect accurate ground surveyed points, a GPS base unit was set up over monuments to

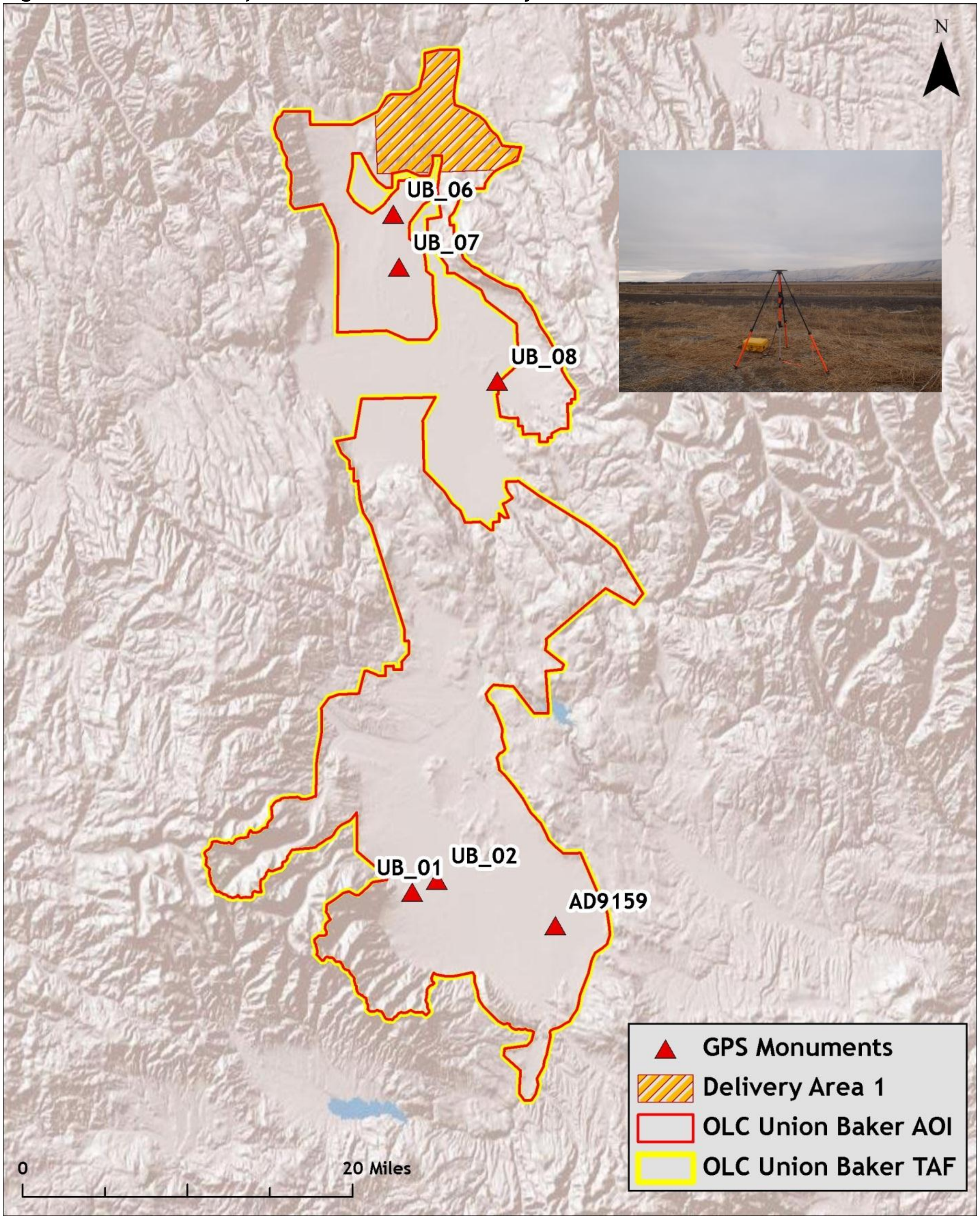
[4] U.S. Army Corps of Engineers , Engineer Research and Development Center Topographic Engineering Center software
[5] Federal Geographic Data Committee Draft Geospatial Positioning Accuracy Standards

broadcast a kinematic correction to a roving GPS unit. The ground crew used a roving unit to receive radio-relayed kinematic corrected positions from the base unit. This RTK survey allowed precise location measurement ($\sigma \leq 1.5$ cm).

***Table 2.2.*** *Base Station Surveyed Coordinates, (NAD83/NAVD88, OPUS corrected) used for kinematic post-processing of the aircraft GPS data for the Union Baker Delivery area 1.*

| | **Datum NAD83 (HARN)** | | **GRS80** |
|---|---|---|---|
| **Base Stations ID** | **Latitude (North)** | **Longitude (West)** | **Ellipsoid Height (m)** |
| UB_01 | 44 52 08.78621 | 117 58 59.55526 | 1064.525 |
| UB_02 | 44 52 44.96607 | 117 57 07.99989 | 1020.506 |
| AD9159 | 44 50 08.88212 | 117 48 30.06107 | 1009.617 |
| UB_06 | 45 27 50.61921 | 117 58 51.85649 | 822.055 |
| UB_07 | 45 25 03.10649 | 117 58 32.52314 | 821.41 |
| UB_08 | 45 18 53.60318 | 117 51 29.65085 | 803.496 |

**Figure 2.2.** *Base stations for the OLC Union Baker Study Area.*



# 3. Accuracy

## 3.1 Relative Accuracy

### Relative Accuracy Calibration Results

Relative accuracy refers to the internal consistency of the data set and is measured as the divergence between points from different flightlines within an overlapping area. Divergence is most apparent when flightlines are opposing. When the LiDAR system is well calibrated the line to line divergence is low (<10 cm). Internal consistency is affected by system attitude offsets (pitch, roll and heading), mirror flex (scale), and GPS/IMU drift.

Relative accuracy statistics are based on the comparison of 130 flightlines and over 6 billion points. Relative accuracy is reported for the portion of the study area shown in **Figure 3.1** below.

- Project Average = 0.11ft (0.03m)
- Median Relative Accuracy = 0.11 ft (0.03 m)
- 1σ Relative Accuracy = 0.11 ft (0.03m)
- 2σ Relative Accuracy = 0.15 ft (0.05 m)

**Figure 3.1.** *Relative Accuracy Covered Area.*

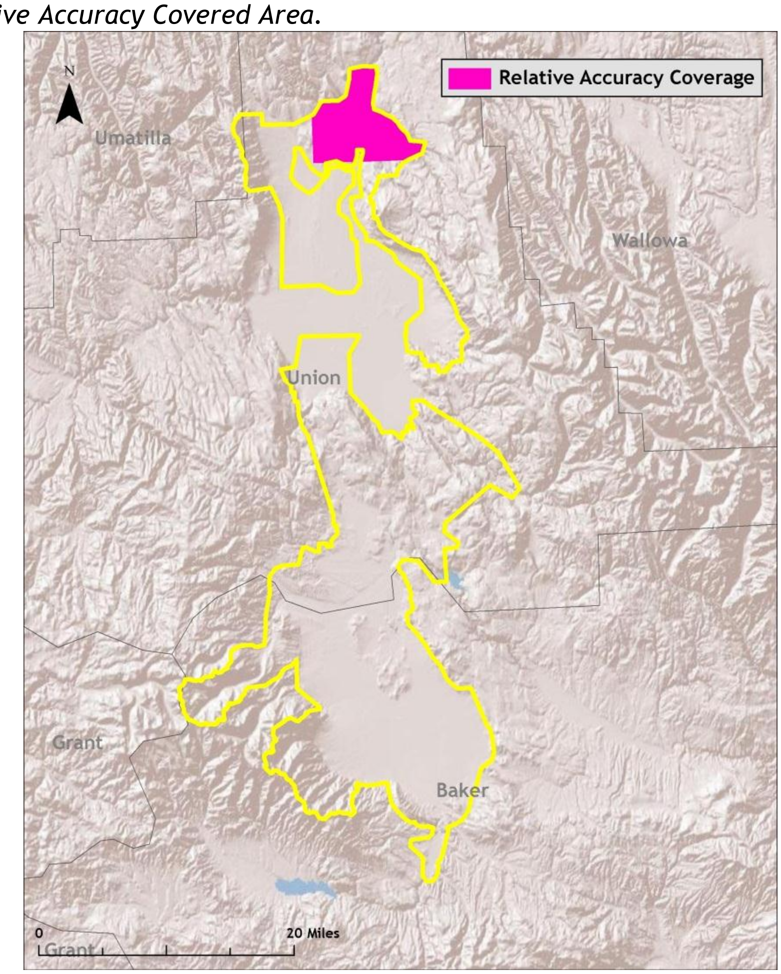


**Figure 3.2.** *Statistical relative accuracies, non slope-adjusted.*

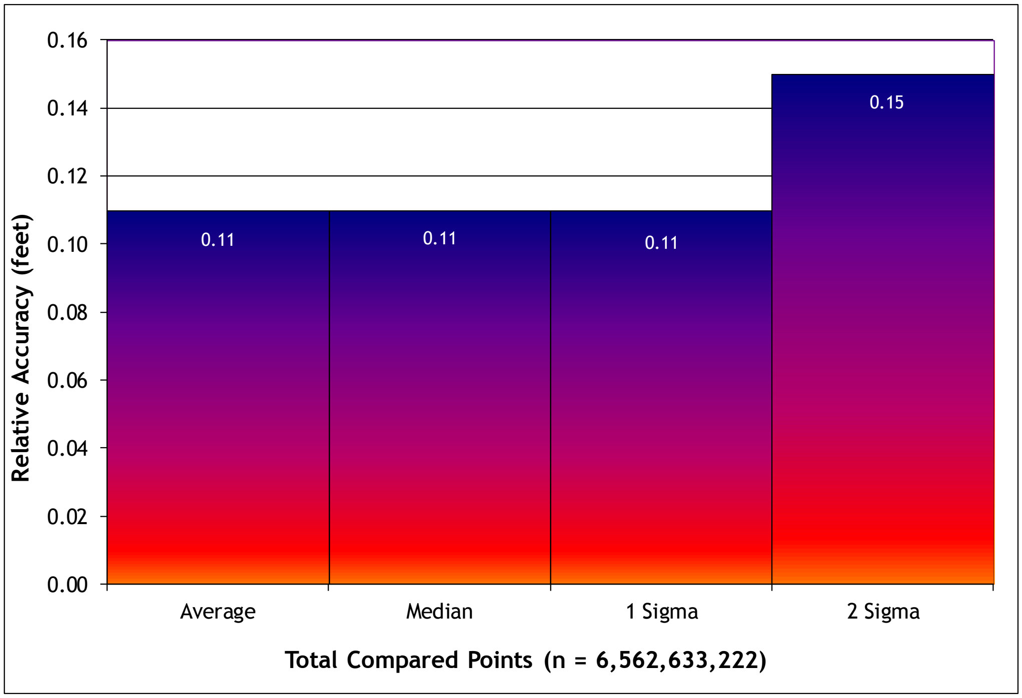
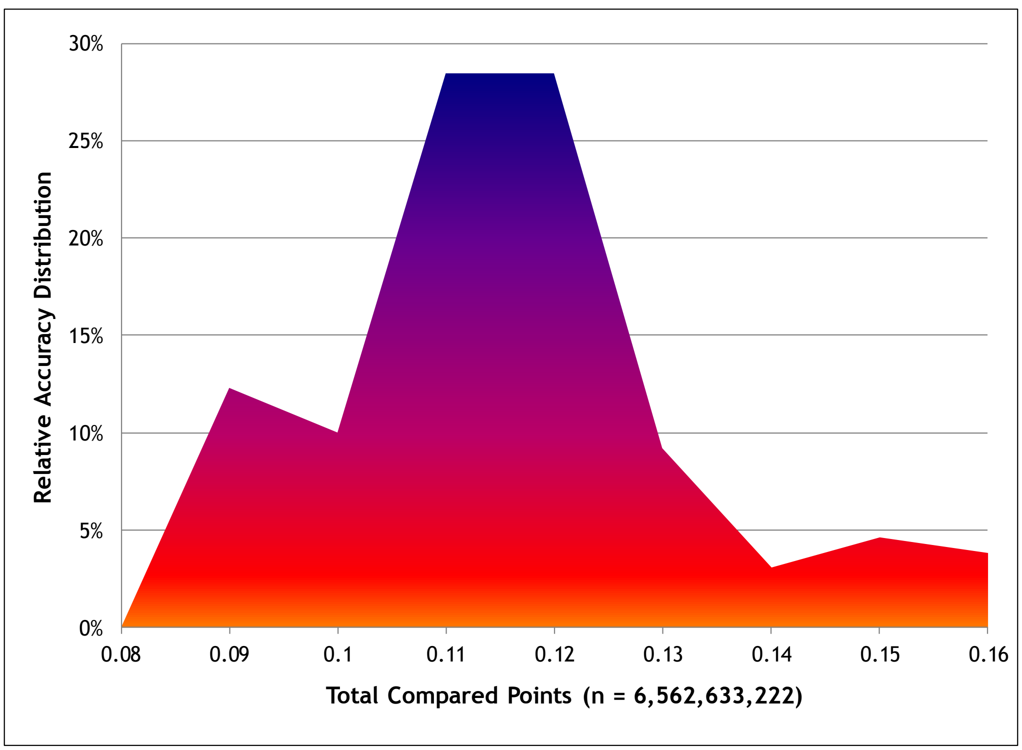



**Figure 3.3.** *Percentage distribution of relative accuracies, non slope-adjusted.*



# 4. Data Density/Resolution

## 4.1 Density Statistics

Some types of surfaces (i.e. dense vegetation or water) may return fewer pulses than the laser originally emitted. Therefore, the delivered density can be less than the native density and vary according to terrain, land cover and water bodies. Density histograms and maps (**Figures 4.1 – 4.4)** have been calculated based on first return laser point density and ground-classified laser point density.

***Table 4.1***. *Average density statistics for OLC Union Baker delivery area 1.*

| Average Pulse Density (per square ft) | Average Pulse Density (per square m) | Average Ground Density (per square ft) | Average Ground Density (per square m) |
|---|---|---|---|
| 0.84 | 9.05 | 0.20 | 2.17 |

***Figure 4.1***. *Histogram of first return laser point density.*

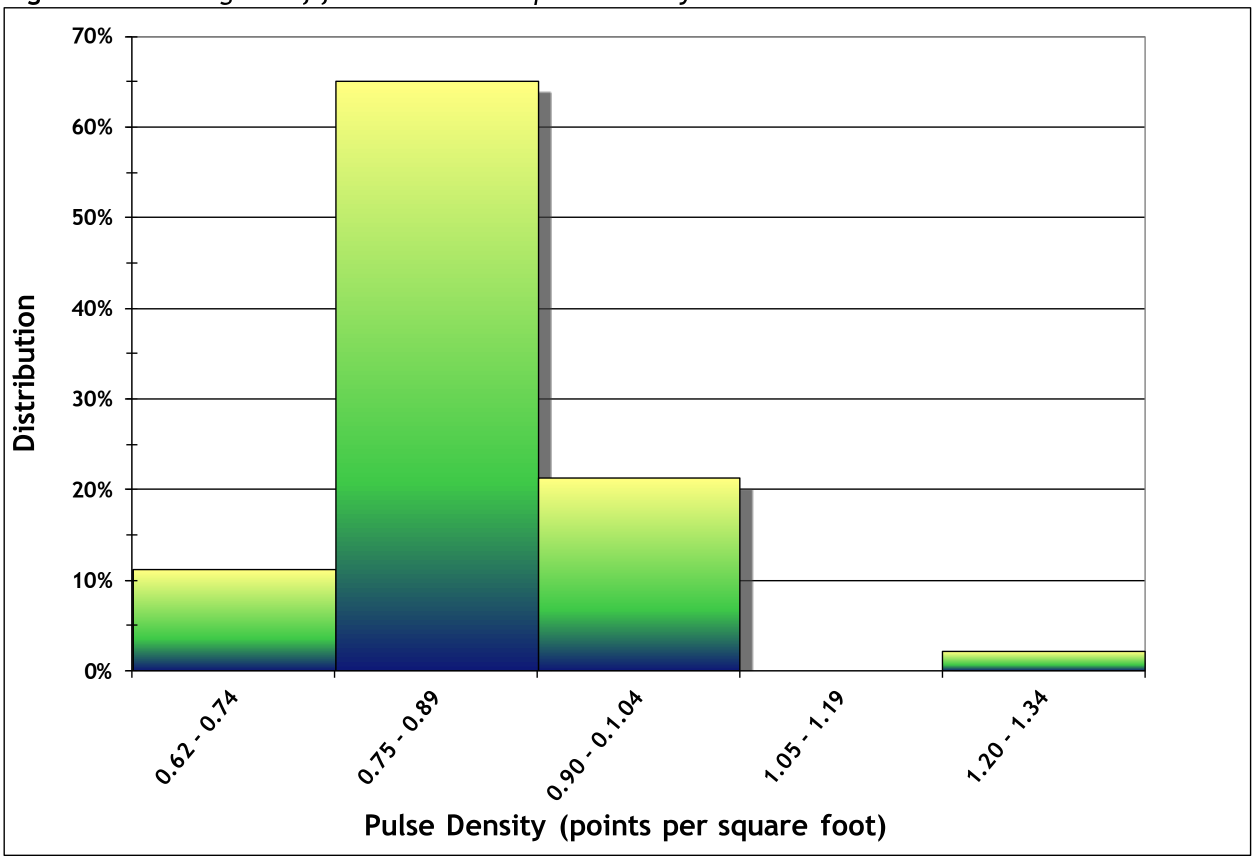
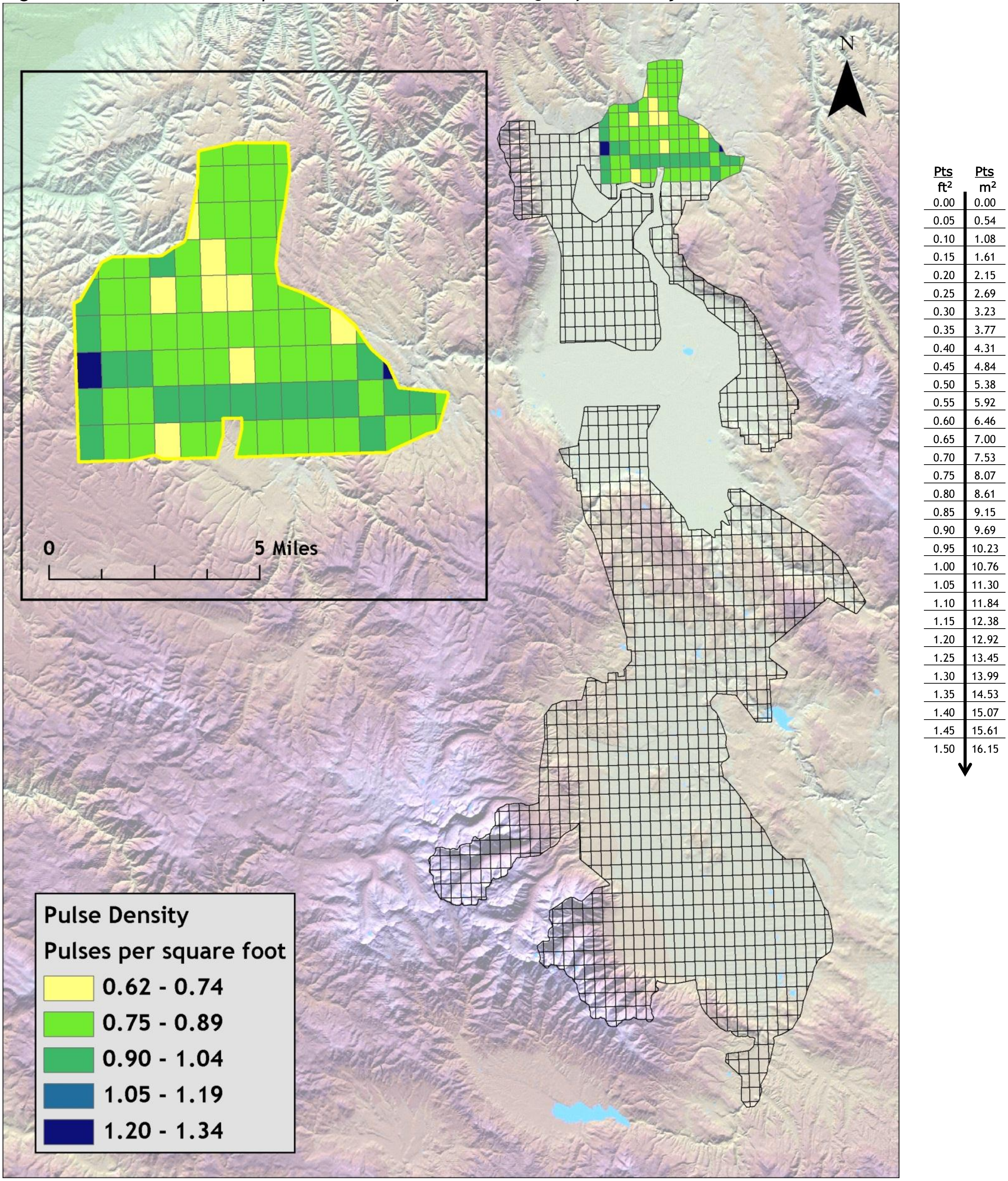


**Figure 4.2.** *First return laser point densities per 0.75' USGS Quad for delivery area 1.*



Ground classifications were derived from ground surface modeling. Classifications were performed by reseeding of the ground model where it was determined that the ground model failed, usually under dense vegetation and/or at breaks in terrain, steep slopes and at bin boundaries.

**Figure 4.3.** *Histogram of ground-classified laser point density.*

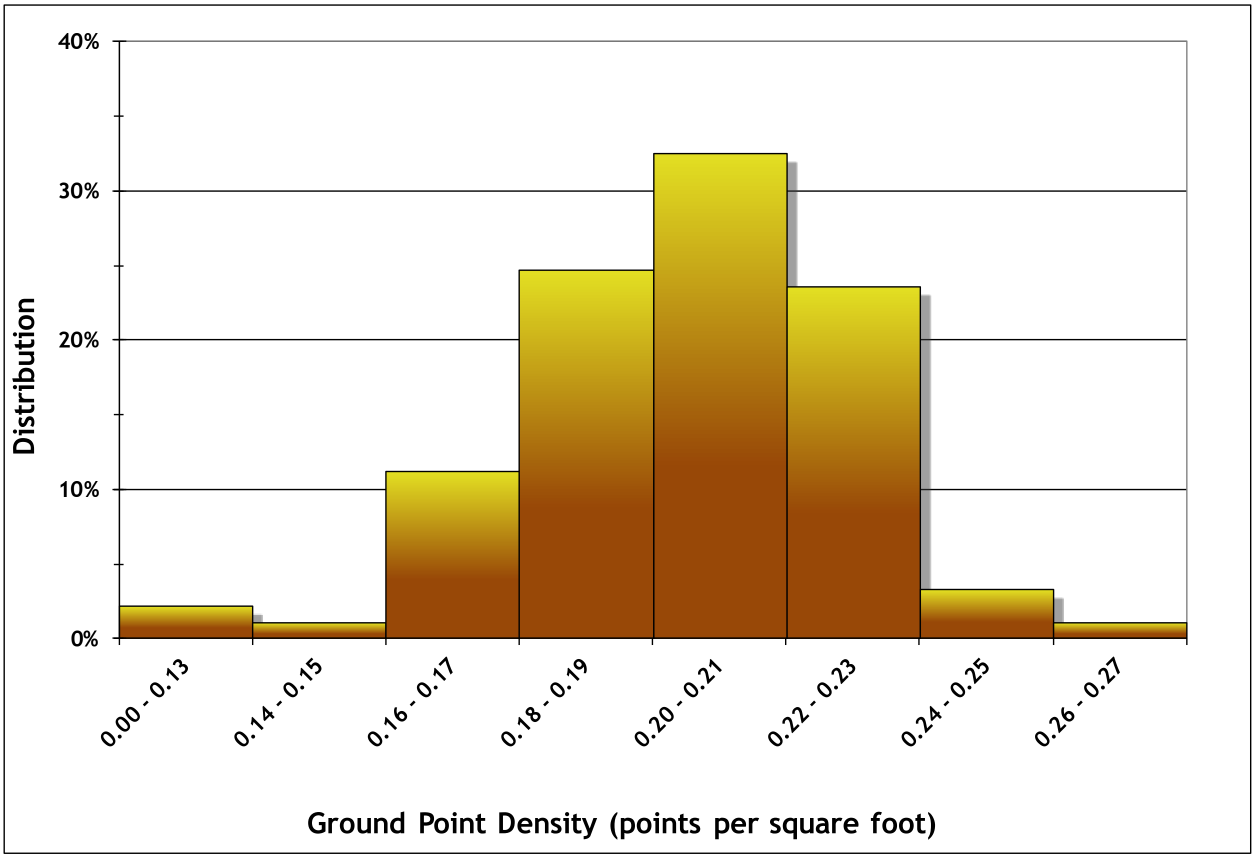
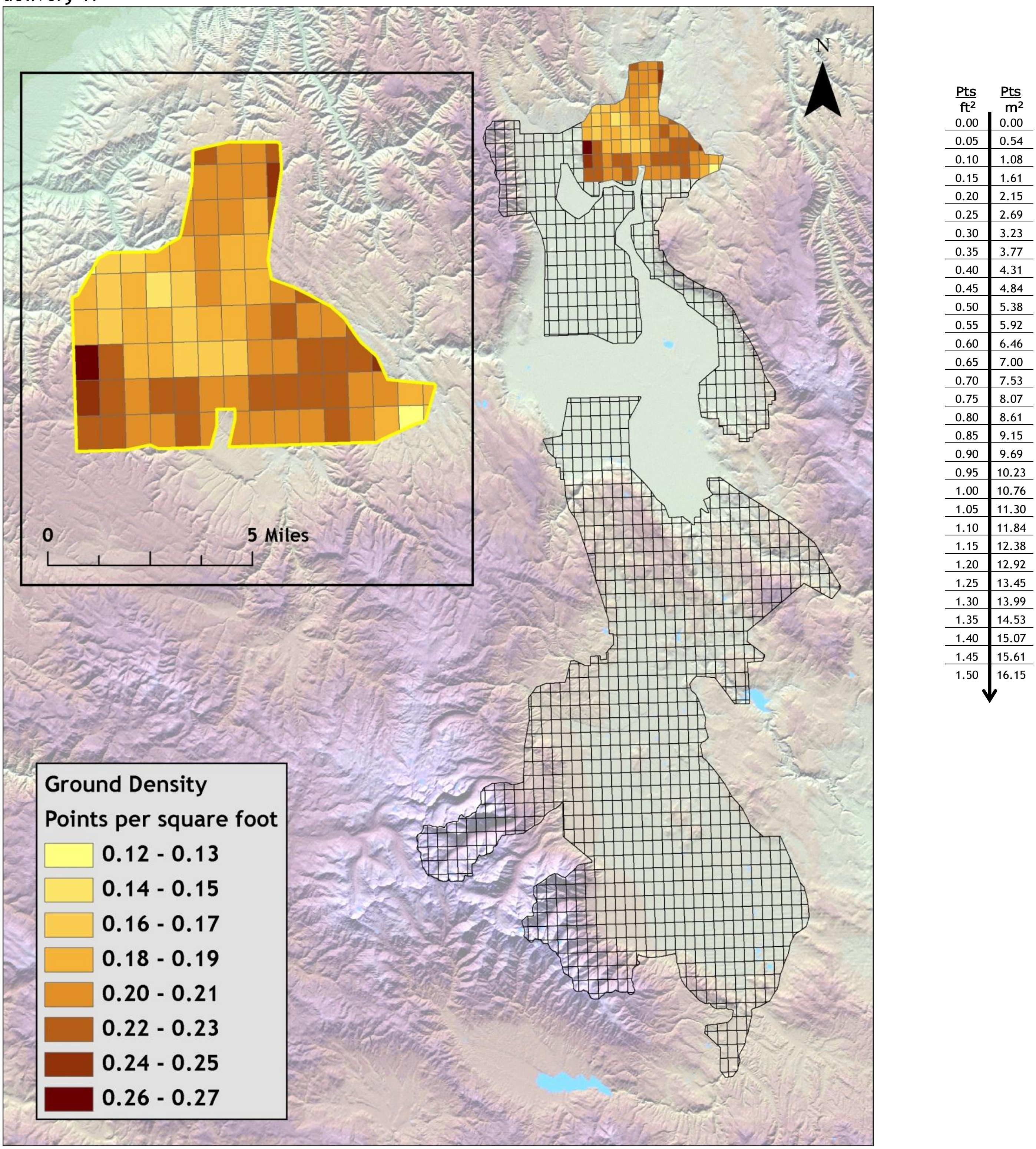


**Figure 4.4.** *Ground-classified laser point density per 0.75' USGS Quad for data delivered to date for delivery 1.*



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## 5. Certifications

Watershed Sciences provided LiDAR services for the Union Baker study area as described in this report.

I, Mathew Boyd, have reviewed the attached report for completeness and hereby state that it is a complete and accurate report of this project.

Mathew Boyd
Principal
Watershed Sciences, Inc.

I, Christopher W. Yotter-Brown, being first dully sworn, say that as described in the Ground Survey subsection of the Acquisition section of this report was completed by me or under my direct supervision and was completed using commonly accepted standard practices. Accuracy statistics shown in the Accuracy Section have been reviewed by me to meet National Standard for Spatial Data Accuracy.

REGISTERED PROFESSIONAL LAND SURVEYOR 1/31/2012

OREGON
JULY 13, 2004
Christopher W. Yotter - Brown
60433 LS

RENEWAL DATE: 6/30/2012

Christopher W. Yotter-Brown, PLS Oregon & Washington
Watershed Sciences, Inc
Portland, OR 97204

## 6. Selected Imagery

**Figure 6.1.** City of Elgin, Union County, Oregon. View to the Southwest (cover image).