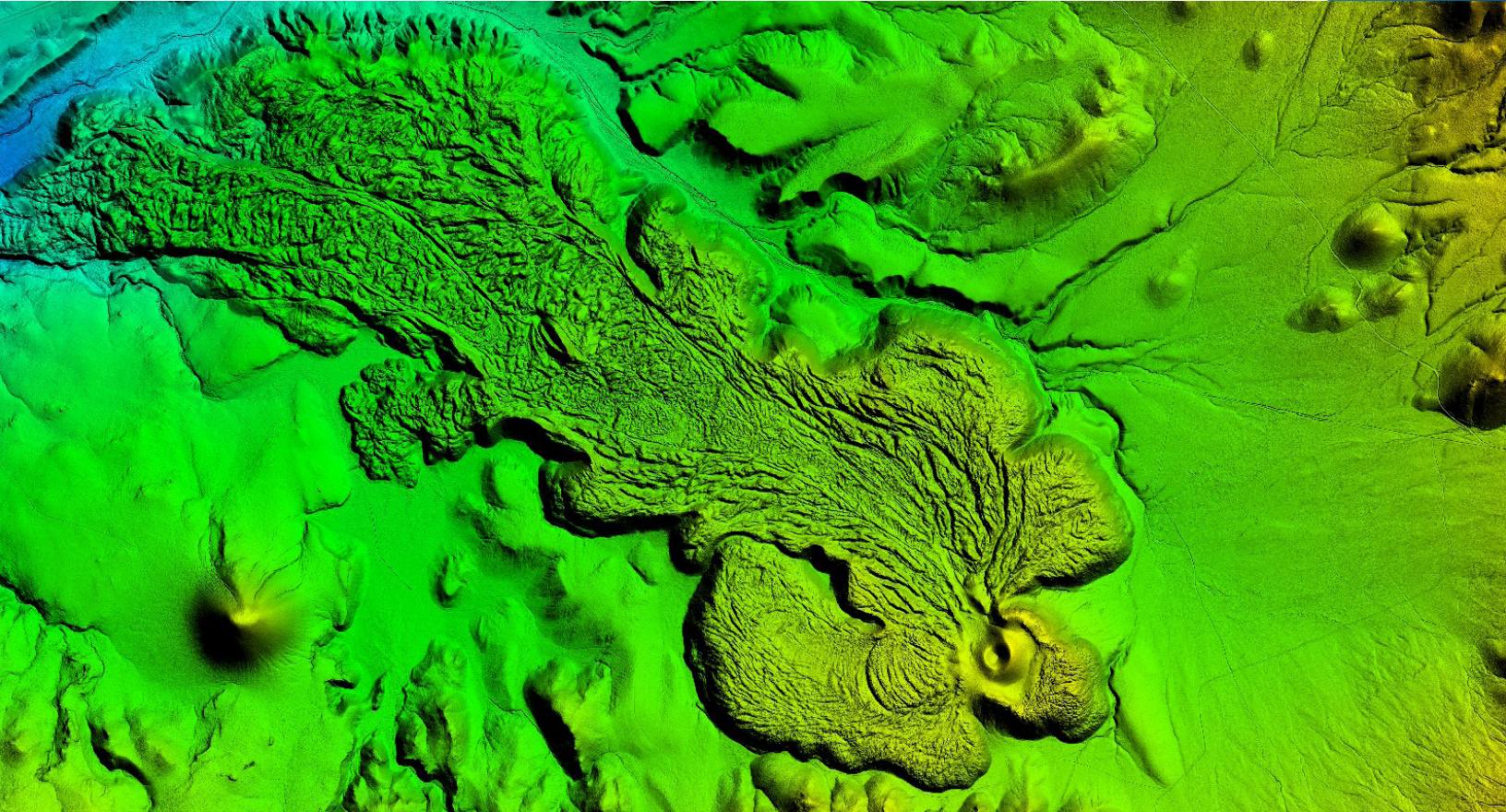


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NV_WestCentral_ EarthMRI_2020_D20 LIDAR PROCESSING REPORT

Project ID: 198162
Work Unit: 198159

Prepared for:



2022

Submitted: September 9, 2022

Prepared by:

N|V|5
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Appendix A: Flight Logs

1. Summary / Scope

1.1. Summary

This report contains a summary of the NV_WestCentral_EarthMRI_2020_D20, Work Unit 198159 lidar acquisition task order, issued by USGS under their Contract G16PC00016 on 09/15/2020. The task order yielded a project area covering approximately 5,455 square miles over Nevada. 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
2 pts / m2	2305 m	58.5°	30%	≤ 10 cm

1.3. Coverage

The project boundary covers approximately 5,455 square miles over Nevada. Project extents are shown in Figure 1.

1.4. Duration

Lidar data was acquired from October 15th, 2020 to November 4th, 2020 in 27 total lifts. See “Section: 2.4. Time Period” for more details.

1.5. Issues

There were no issues to report.

NV_WestCentral_EarthMRI_2020_D20 Work Unit 198159 Projected Coordinate System: UTM Zone 11N Horizontal Datum: NAD83(2011) Vertical Datum: NAVD88 (GEOID 18) Units: Meters	
Lidar Point Cloud	Classified Point Cloud in .LAS 1.4 format
Rasters	<ul style="list-style-type: none"> • 1-meter Hydro-flattened Bare Earth Digital Elevation Model (DEM) in GeoTIFF format • 1-meter Intensity images in GeoTIFF format
Vectors	Shapefiles (*.shp) <ul style="list-style-type: none"> • Project Boundary • Lidar Tile Index • Calibration and QC Checkpoints (NVA/VVA) • Building Footprint Polygons Geodatabase (*.gdb) <ul style="list-style-type: none"> • Continuous Hydro-flattened Breaklines
Reports	Reports in PDF format <ul style="list-style-type: none"> • Focus on Delivery • Focus on Accuracy • Processing Report
Metadata	XML Files (*.xml) <ul style="list-style-type: none"> • Breaklines • Classified Point Cloud • DEM • Intensity Imagery

NV_WestCentral_EarthMRI_2020_D20 Work Unit 198159 Boundary

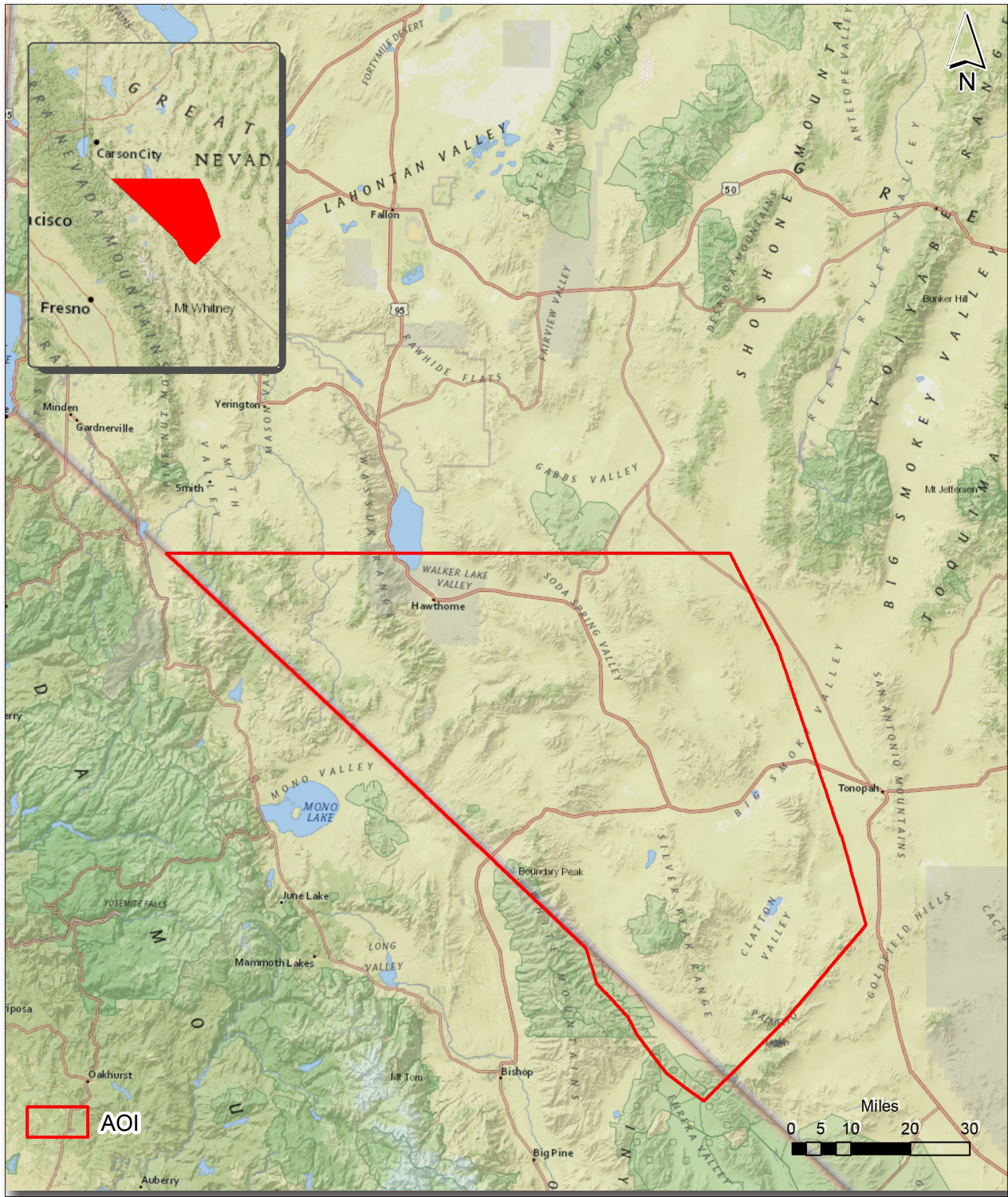


Figure 1. Work Unit Boundary

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 Leica Terrain Mapper planning software.

2.2. Lidar Sensor

NV5 Geospatial utilized a Leica Terra Mapper lidar sensor (Figure 2) for data acquisition.

Aerial LiDAR data was collected utilizing a Lecia Terrain Mapper. The Terrain Mapper is a discrete return topographic LiDAR mapping system manufactured by Leica Geosystems.

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

		Terra Mapper (TM_9054)
Terrain and Aircraft Scanner	Flying Height	2,800 m
	Recommended Ground Speed	165 kts
Scanner	Field of View	40°
	Scan Rate Setting Used	92.3 Hz
Laser	Laser Pulse Rate Used	650 kHz
	Multi Pulse in Air Mode	yes
Coverage	Full Swath Width	2,016 m
	Line Spacing	1,411 m
Point Spacing and Density	Average Point Spacing	0.65 m
	Average Point Density	2 pts / m ²

Figure 2. Terra Mapper Lidar Sensor



2.3. Aircraft

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

Lidar Collection Planes

- Cessna Conquest 2 (twin-turboprop), Tail Number(s): N207SS

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 TM_9054 lidar system. Some of NV5 Geospatial’s operating aircraft can be seen in Figure 3 below.

Figure 3. Some of NV5 Geospatial’s Planes



2.4. Time Period

Project specific flights were conducted between October 15th, 2020 and November 4th, 2020. Twenty-Seven aircraft lifts were completed. Accomplished lifts are listed below.

- 20201015154055
- 20201015214029
- 20201016160448
- 20201016212443
- 20201017153134
- 20201017233020
- 20201018153433
- 20201019153450
- 20201019220635
- 20201020153032
- 20201020215328
- 20201021153349
- 20201022190618
- 20201023011115
- 20201023045845
- 20201023161702
- 20201023221044
- 20201024164840
- 20201026163842
- 20201027154831
- 20201027220902
- 20201028152217
- 20201028212920
- 20201029151957
- 20201029212657
- 20201030153459
- 20201030173615
- 20201031155542
- 20201031201122
- 20201104171729

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

Inertial Explorer 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 Inertial Explorer 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 Leica HxMap 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
Leica HxMap	2.6.0
Inertial Explorer	8.90
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 2.1 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
9	Water	Laser returns that are found inside of hydro features
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
20	Ignored Ground	Ground points that fall within the given threshold of a collected hydro feature.

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 3 feet/1 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

Class 2 lidar was used to create a bare earth surface model. The surface model was then used to heads-up digitize 2D breaklines of Inland Streams and Rivers with a 100 foot nominal width and Inland Ponds and Lakes of 2 acres or greater surface area.

Elevation values were assigned to all Inland streams and rivers using NV5 Geospatial’s proprietary software.

All ground (ASPRS Class 2) lidar data inside of the collected inland breaklines were then classified to water (ASPRS Class 9) using TerraScan macro functionality. A buffer of 3 feet was also used around each hydro-flattened feature. These points were moved from ground (ASPRS Class 2) to Ignored Ground (ASPRS Class 20).

The breakline files were then translated to Esri file geodatabase format using Esri conversion tools.

Breaklines are reviewed against lidar intensity imagery to verify completeness of capture. All breaklines are then compared to TINs (triangular irregular networks) created from ground only points prior to water classification. The horizontal placement of breaklines is compared to terrain features and the breakline elevations are compared to lidar elevations 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 variance is reviewed, all breaklines are reviewed for topological consistency and data

integrity using a combination of Esri Data Reviewer tools and proprietary tools.

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 value-units. Appropriate horizontal and vertical projection information as well as applicable header values are written 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

GeoCue software was used to create the deliverable intensity images. All withheld points were ignored during this process. This helps to ensure a more aesthetically pleasing image. The GeoCue software was then used to verify full project coverage as well. GeoTIFF files with a cell size of 1-meter were then provided as the deliverable for this dataset requirement.

3.8. Height 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

NV_WestCentral_EarthMRI_2020_D20 Work Unit 198159 Tile Layout

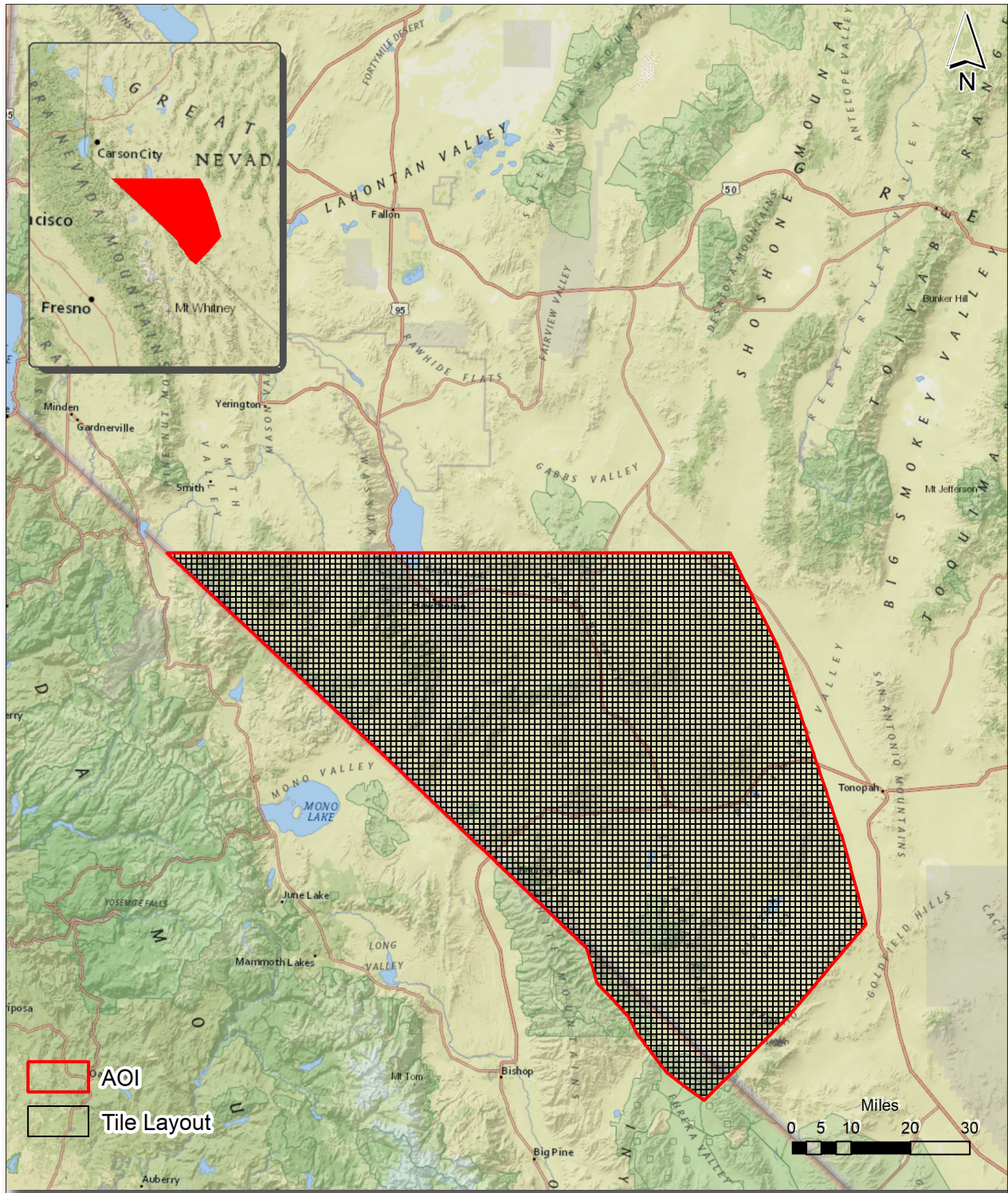


Figure 4. Lidar Tile Layout

4. Project Coverage Verification

Coverage verification was performed by comparing coverage of processed .LAS files captured during project collection to generate project shape files depicting boundaries of specified project areas. Please refer to Figure 5.

NV_WestCentral_EarthMRI_2020_D20 Work Unit 198159 Lidar Coverage

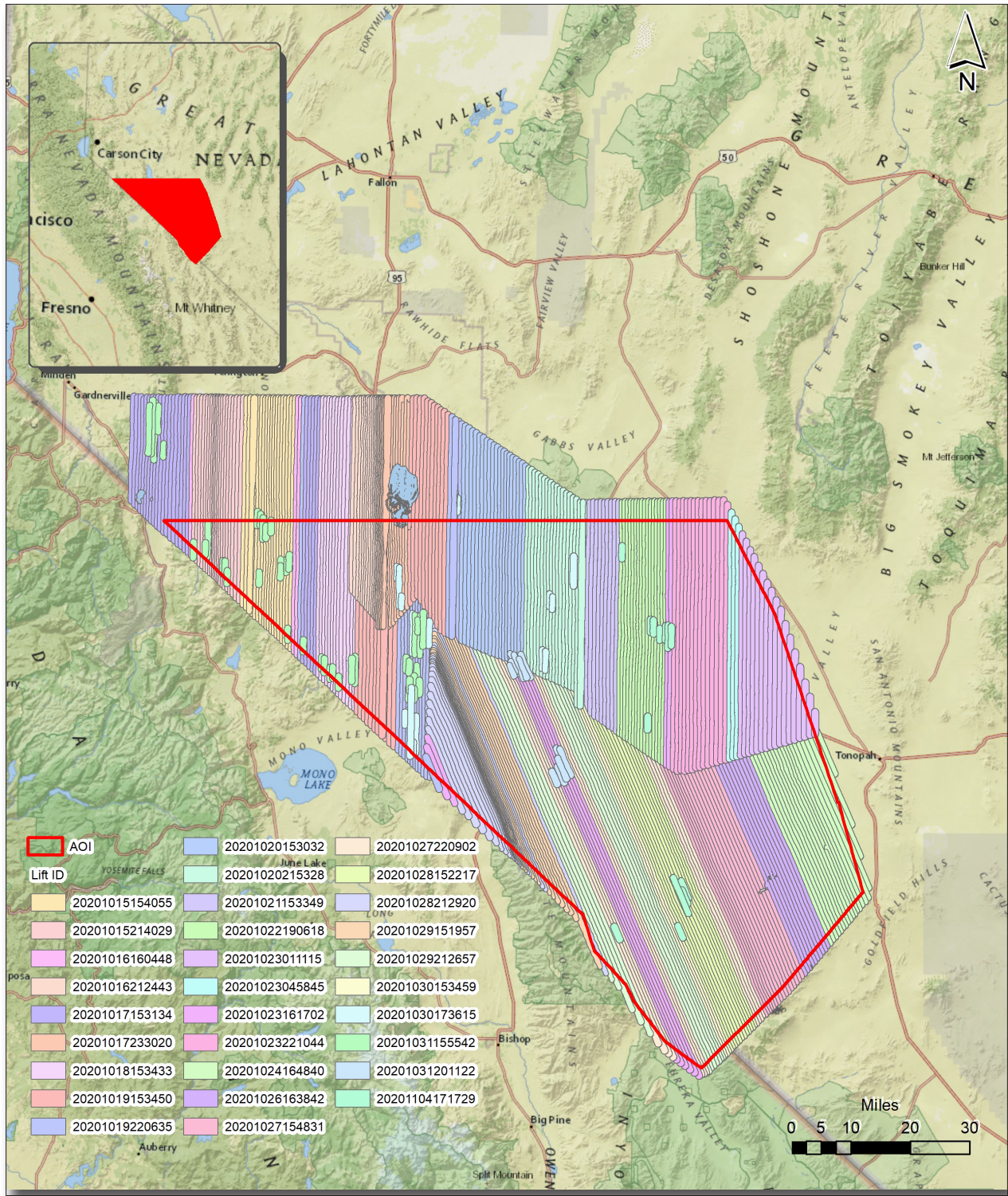


Figure 5. Lidar Coverage

6. Geometric Accuracy

6.1. Horizontal Accuracy

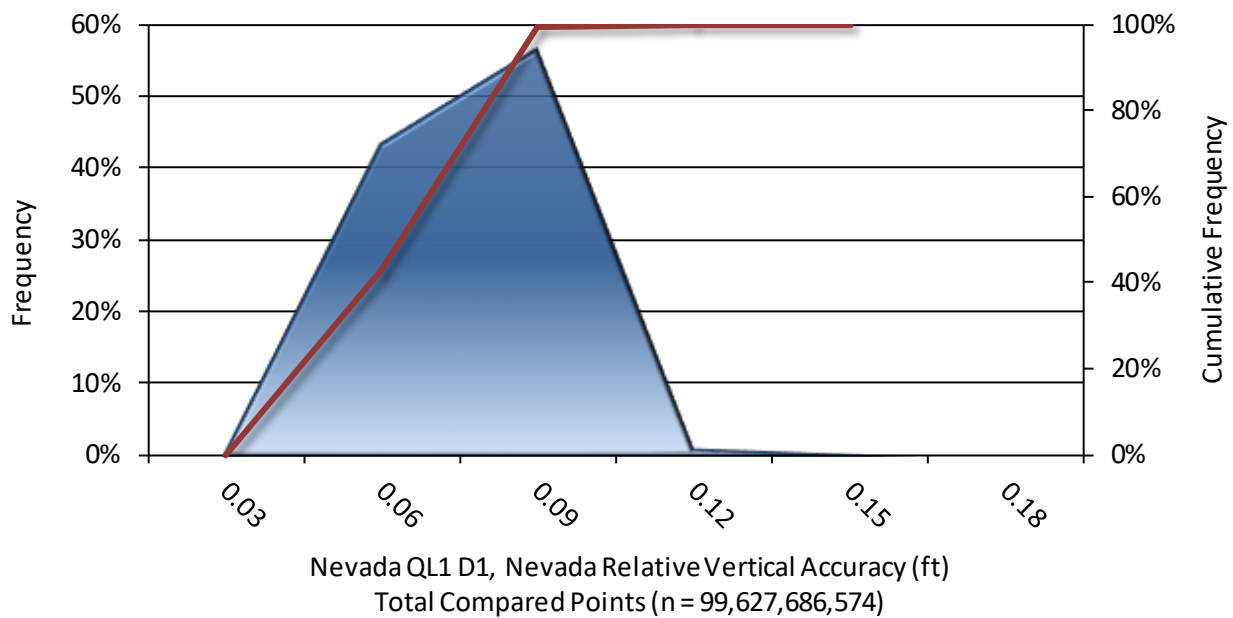
Lidar horizontal accuracy is a function of Global Navigation Satellite System (GNSS) derived positional error, flying altitude, and INS derived attitude error. The obtained $RMSE_r$ value is multiplied by a conversion factor of 1.7308 to yield the horizontal component of the National Standards for Spatial 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 2800 meters, an IMU error of 0.002 decimal degrees, and a GNSS positional error of 0.015 meters, this project was compiled to meet 0.12 meter horizontal accuracy at the 95% confidence level. A summary is shown below.

Horizontal Accuracy	
$RMSE_r$	0.58 ft
	0.17 m
ACC_r	1 ft
	0.30 m

6.2. 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 NV_WestCentral_EarthMRI_2020_D20 project was 0.06 feet (0.018 meters). A summary is shown below.

Relative Vertical Accuracy	
Sample	444 flight line surfaces
Average	.06 ft
	.018 m
Median	.061 ft
	.019 m
RMSE	.062 ft
	.019 ft
Standard Deviation (1σ)	.007 ft
	.002 m
1.96σ	.014 ft
	.004 m



Project Report Appendices

The following section contains the appendices as listed in the **NV_WestCentral_EarthMRI_2020_D20 Lidar Project Report**.

Appendix A

Flight Logs



Digital Aerial Solutions Flight Log

Project/Flight Plan:		Nevada Earth			Lift	Temp °C Before	Temp °C After	Pressure (kPa)			Sensor Operator			
					5	4	24	102.51			Chuck Harris			
Date/Julian:		10/17/2020			Disk Drive			Sensor			Pilot			
Hobbs End		7208.6			TM MM30 (103, 104)			TM_90524			Anthony Kosinski			
Hobbs ST		7203			TARGET MSL	Target AIRSPD	Base Name	PID	Base Name	PID	Base Height	Aircraft	Airport Identification:	
Flight Time		5.6			13,500		165	KMEV01		KMEV02		1.500	C441-N207SS	Minden (KMEV)
∠	Flight Line	Mission Line	UTC time:		Direction	GPS Altitude	Speed	Available	S/Vs	Position Acc.		Comments and Conditions:		
			Begin:	End:				MM Space		AVG PDOP	AVG HDOP			
	19	19 S	15:53	16:01	167°	13532	160	6831	18	1.1	0.7	Gimbal data from PAV missing		
	18	18 N	16:06	16:14	347°	13512	155	6826	18	1.3	0.7			
	17	17 S	16:19	16:27	167°	13610	161	6819	18	1.3	0.7	" "		
	16	16 N	16:32	16:40	347°	13608	158	6813	18	1.3	0.7			
	15	15 S	16:44	16:52	167°	13767	159	6807	17	1.3	0.7			
	14	14 N	16:57	17:05	347°	13914	161	6802	18	1.2	0.7			
	13	13 S	17:08	17:16	167°	14014	158	6797	20	1.1	0.6			
	12	12 N	17:20	17:28	347°	14007	156	6792	21	1.0	0.6			
	11	11 S	17:32	17:39	167°	14000	158	6786	21	1.0	0.6	" "		
	10	10 N	17:44	17:51	347°	14017	158	6779	19	1.0	0.6			
	9	9 S	17:55	18:02	167°	14003	156	6774	18	1.1	0.7			
	8	8 N	18:06	18:13	347°	14005	154	6769	17	1.3	0.8			
	7	7 S	18:17	18:24	167°	14006	164	6763	16	1.4	0.8	" "		
	6	6 N	18:29	18:35	347°	13990	158	6757	19	1.2	0.8			
	5	5 S	18:39	18:45	167°	13996	164	6752	19	1.4	0.8			
	4	4 N	18:51	18:56	347°	14015	155	6745	19	1.4	0.8			
	3	3 S	19:00	19:06	166°	14028	160	6741	20	1.3	0.7			
	2	2 N	19:11	19:17	346°	14032	158	6736	20	1.3	0.7			
	1	1 S	19:21	19:27	166°	14250	162	6733	22	1.2	0.7			
	62	62 N	19:39	19:53	347°	13648	164	6727	24	1.0	0.6			
	63	63 S	19:57	20:12	166°	13671	162	6716	23	1.1	0.6			
	64	64 N	20:16	20:31	346°	13673	158	6704	23	1.2	0.6			
	65	65 S	20:35	20:49	167°	13718	165	6694	24	1.2	0.6			
	66	66 N	20:54	21:09	347°	13742	154	6682	23	1.2	0.6			



Digital Aerial Solutions Flight Log

Project/Flight Plan:		Nevada Earth			Lift	Temp °C Before	Temp °C After	Pressure (kPa)			Sensor Operator			
					8	6	26	102.40			Chuck Harris			
Date/Julian:		10/18/2020			Disk Drive			Sensor			Pilot			
Hobbs End		7224.8			TM MM30 (103, 104)			TM_90524			Anthony Kosinski			
Hobbs ST		7219.2			TARGET MSL	Target AIRSPD	Base Name	PID	Base Name	PID	Base Height	Aircraft	Airport Identification:	
Flight Time		5.6			13,500		165	KMEV01		KMEV02		1.500	C441-N207SS	Minden (KMEV)
∠	Flight Line	Mission Line	UTC time:		Direction	GPS Altitude	Speed	Available	S/Vs	Position Acc.		Comments and Conditions:		
			Begin:	End:				MM Space		AVG PDOP	AVG HDOP			
	80	80 S	16:01	16:09	168°	15351	154	6506	22	1.1	0.7	Gimbal PAV warning		
	81	81 N	16:13	16:21	347°	15407	154	6499	21	1.1	0.7			
	82	82 S	16:24	16:32	167°	15500	157	9494	19	1.4	0.7			
	83	83 N	16:35	16:43	348°	15588	158	6489	19	1.3	0.7			
	84	84 S	16:47	16:54	167°	15719	156	6484	19	1.3	0.7			
	85	85 N	16:58	17:05	348°	15751	165	6477	21	1.1	0.6			
	86	86 S	17:09	17:17	167°	15802	156	6472	22	1.0	0.6			
	87	87 N	17:20	17:28	346°	15820	162	6467	20	1.0	0.6			
	88	88 S	17:32	17:39	167°	15800	166	6462	22	1.0	0.6			
	89	89 N	17:43	17:51	347°	16075	166	6456	21	1.0	0.6			
	90	90 S	17:54	18:03	167°	16139	154	6449	21	1.0	0.6			
	261	261 N	18:17	18:28	347°	13003	160	6443	19	1.3	0.8			
	262	262 S	18:32	18:43	166°	12980	163	6435	24	1.4	0.8			
	263	263 N	18:47	18:58	348°	13008	148	6427	21	1.5	0.7			
	264	264 S	19:02	19:14	167°	12986	161	6420	20	1.5	0.7			
	265	265 N	19:17	19:29	346°	13030	155	6412	22	1.2	0.6			
	266	266 S	19:32	19:44	167°	13074	157	6403	25	1.0	0.5			
	267	267 N	19:47	20:00	347°	13040	161	6394	24	1.0	0.6			
	268	268 S	20:03	20:14	167°	13073	160	6383	25	1.1	0.6			
	269	269 N	20:18	20:30	347°	13100	162	6376	22	1.2	0.6			
	270	270 S	20:34	20:46	167°	13171	157	6368	22	1.2	0.6			
	271	271 N	20:51	21:03	347°	13191	161	6359	21	1.2	0.6			



Digital Aerial Solutions Flight Log

Project/Flight Plan:		Nevada Earth			Lift	Temp °C Before	Temp °C After	Pressure (kPa)			Sensor Operator	
					14	15	8	101.62			Chuck Harris	
Date/Julian:	10/22/2020		Disk Drive			Sensor					Pilot	
Hobbs End	7256		TM MM30 (103, 104)			TM_90524					Anthony Kosinski	
Hobbs ST	7251.1		TARGET MSL	Target AIRSPD	Base Name	PID	Base Name	PID	Base Height	Aircraft	Airport Identification:	
Flight Time	4.9		13,500		165	KTPH01		KTPH02		1.500	C441-N207SS	Tonopah (KTPH)
∠	Flight Line	Mission Line	UTC time:		Direction	GPS Altitude	Speed	Available	S/Vs	Position Acc.		Comments and Conditions:
			Begin:	End:				MM Space		AVG PDOP	AVG HDOP	
	374	374 N	1:35	1:36	348°	13892	150	6096	23	1.0	0.6	
	373	373 S	1:40	1:43	167°	13894	155	6095	21	1.2	0.7	Gimbal warning
	372	372 N	1:47	1:50	348°	13865	157	6095	21	1.2	0.7	
	371	371 S	1:54	1:59	167°	13841	157	6094	21	1.2	0.7	Gimbal warning
	370	370 N	2:02	2:07	347°	13816	155	6090	20	1.3	0.7	
	369	369 S	2:12	2:18	167°	13857	155	6086	17	1.5	0.8	Gimbal warning
	368	368 N	2:22	2:28	347°	13850	153	6083	17	1.5	0.8	
	367	367 S	2:33	2:40	167°	13839	157	6078	18	1.3	0.7	
	366	366 N	2:44	2:52	347°	13846	152	6072	18	1.3	0.7	
	365	365 S	2:56	3:05	168°	13827	155	6066	17	1.3	0.7	
	364	364 N	3:08	3:18	347°	13827	155	6062	19	1.3	0.7	
	363	363 S	3:22	3:31	167°	13841	163	6055	21	1.1	0.6	
	362	362 N	3:35	3:46	348°	13831	150	6048	20	1.1	0.6	
	361	361 S	3:49	4:00	166°	13819	155	6042	20	1.2	0.6	
	360	360 N	4:04	4:15	348°	13808	157	6034	22	1.2	0.6	
	359	359 S	4:19	4:31	167°	13802	153	6027	22	1.2	0.6	
	358	358 N	4:35	4:47	348°	13871	161	6018	23	1.1	0.6	
	357	357 S	4:51		167°	13961	159	6009	23	1.2	0.6	FlightPro Froze (04:53) - Airstart
	357	357 N	5:14	5:27	347°	13932	155	6007	28	1.0	0.5	
	356	356 S	5:31	5:44	167°	14051	153	5998	27	1.0	0.5	
	355	355 N	5:48	6:02	348°	14065	158	5989	23	1.1	0.6	



Digital Aerial Solutions Flight Log

Project/Flight Plan:		Nv_Earth			Lift	Temp °C Before	Temp °C After	Pressure (kPa)			Sensor Operator		
					24	3	18	102.51			Chuck Harris		
Date/Julian:		10/30/2020		Disk Drive			Sensor					Pilot	
Hobbs End		7313.6		TM MM30 (103, 104)			TM_90524					Wes Ashmore	
Hobbs ST		7309		TARGET MSL	Target AIRSPD	Base Name	PID	Base Name	PID	Base Height	Aircraft	Airport Identification:	
Flight Time		4.6		13,500		165	KTPH01		KTPH02		1.500	C441-N207SS	Tonopah, NV (KTPH)
∠	Flight Line	Mission Line	UTC time:		Direction	GPS Altitude	Speed	Available	S/Vs	Position Acc.		Comments and Conditions:	
			Begin:	End:				MM Space		AVG PDOP	AVG HDOP		
	168	168 S	16:08	16:31	144°	13624	158	4984	20	1.1	0.6		
	169	169 N	16:35	16:58	324°	13691	156	4966	19	1.0	0.6		
	170	170 S	17:02	17:26	144°	13745	160	4949	17	1.2	0.7		
	455	455 N	17:52	17:53	347°	14952	161	4931	16	1.4	0.8		
	454	454 S	17:56	17:57	166°	14928	162	4929	17	1.4	0.7		
	456	456 N	18:03	18:04	346°	14532	155	4929	18	1.3	0.7		
	457	457 S	18:07	18:08	167°	14650	161	4928	18	1.3	0.7		
	458	458 N	18:12	18:13	347°	13525	161	4926	18	1.3	0.7		
	452	452 N	18:22	18:22	347°	14740	160	4924	18	1.3	0.7		
	453	453 S	18:26	18:27	167°	14519	163	4924	19	1.3	0.7		
	450	450 S	18:33	18:34	167°	14458	163	4924	20	1.2	0.6		
	437	437 N	18:39	18:41	347°	15239	158	4923	21	1.1	0.6		
	431	431 S	18:45	18:48	167°	15211	159	4921	21	1.1	0.6		
	430	430 N	18:50	18:52	347°	14360	157	4921	22	1.0	0.5		
	429	429 S	18:56	18:57	167°	14307	161	4919	22	1.0	0.6		
	461	461 N	19:01	19:02	347°	15610	165	4918	20	1.1	0.6		
	463	463 N	19:03	19:05	347°	15235	145	4916	21	1.1	0.6		
	462	462 N	19:10	19:11	347°	14200	159	4914	21	1.1	0.6		
	433	433 S	19:26	19:27	167°	16498	164	4913	21	1.1	0.6		
	432	432 N	19:31	19:32	347°	16430	159	4912	21	1.2	0.6		
	446	446 S	19:36	19:40	167°	16275	159	4911	21	1.2	0.6		
	448	448 N	19:43	19:44	347°	16152	163	4907	21	1.1	0.6		
	447	447 S	19:49	19:51	167°	16095	160	4907	20	1.3	0.6		
	459	459 N	19:56	19:57	347°	16080	158	4905	22	1.1	0.6		



Digital Aerial Solutions Flight Log

Project/Flight Plan:		Nv_Earth			Lift	Temp °C Before	Temp °C After	Pressure (kPa)			Sensor Operator			
					26	2	23	102.71			Geoffrey McCall			
Date/Julian:		10/31/2020			Disk Drive			Sensor			Pilot			
Hobbs End		7319.9			TM MM30 (101, 102)			TM_90524			Wes Ashmore			
Hobbs ST		7314.3			TARGET MSL	Target AIRSPD	Base Name	PID	Base Name	PID	Base Height	Aircraft	Airport Identification:	
Flight Time		5.6			14,692		165	KMEV01		KMEV02		1.500	C441-N207SS	KMEV
∠	Flight Line	Mission Line	UTC time:		Direction	GPS Altitude	Speed	Available	S/Vs	Position Acc.		Comments and Conditions:		
			Begin:	End:				MM Space		AVG PDOP	AVG HDOP			
	65	465s	16:20	16:22	170°	15733	155	5205	20	1.1	0.7			
	64	464n	16:26	16:29	346°	15717	162	5203	22	1.0	0.6			
	1	401s	16:33	16:36	167°	15400	153	5200	20	1.1	0.6			
	2	402n	16:40	16:41	345°	15408	152	5200	18	1.1	0.7			
	3	403s	16:46	16:47	167°	15033	161	5200	16	1.2	0.7			
	23	423s	16:52	16:53	167°	16169	155	5198	18	1.2	0.7			
	25	425n	16:56	16:57	346°	15611	165	5197	18	1.1	0.7			
	24	424s	17:01	17:03	168°	15162	163	5197	18	1.1	0.7			
	26	426n	17:08	17:09	347°	15919	158	5195	18	1.1	0.7			
	27	427s	17:13	17:14	166°	15883	158	5193	18	1.1	0.7			
	28	428n	17:18	17:19	347°	16073	158	5193	18	1.2	0.7			
	12	412n	17:22	17:23	345°	15855	154	5193	17	1.4	0.8			
	13	413s	17:27	17:27	167°	15958	155	5190	17	1.4	0.8			
	16	416s	17:30	17:31	167°	15331	160	5190	17	1.4	0.8			
	14	414n	17:35	17:36	347°	15940	166	5190	19	1.4	0.8			
	15	415s	17:41	17:41	166°	16019	158	5190	19	1.4	0.8			
	17	417n	17:46	17:47	347°	16277	157	5190	19	1.4	0.8			
	20	420s	17:52	17:53	167°	15956	161	5190	19	1.4	0.8			
	18	418n	17:56	17:57	345°	15817	154	5189	19	1.4	0.8			
	21	421s	18:01	18:02	167°	15547	156	5189	20	1.3	0.7			
	19	419n	18:05	18:06	346°	15544	163	5189	20	1.3	0.7			
	22	422s	18:13	18:13	166°	15545	160	5189	20-	1.3	0.7			
	60	460n	18:17	18:18	348°	15590	162	5187	20	1.3	0.7			
	4	404s	18:21	18:22	167°	15591	161	5187	20	1.3	0.7			
	5	405n	18:26	18:26	347°	15879	156	5186	21	1.3	0.8			

