Optical Remote Sensing with Coherent Doppler LIDAR

Part 2: Detection, Processing, and Analysis of LIDAR signals

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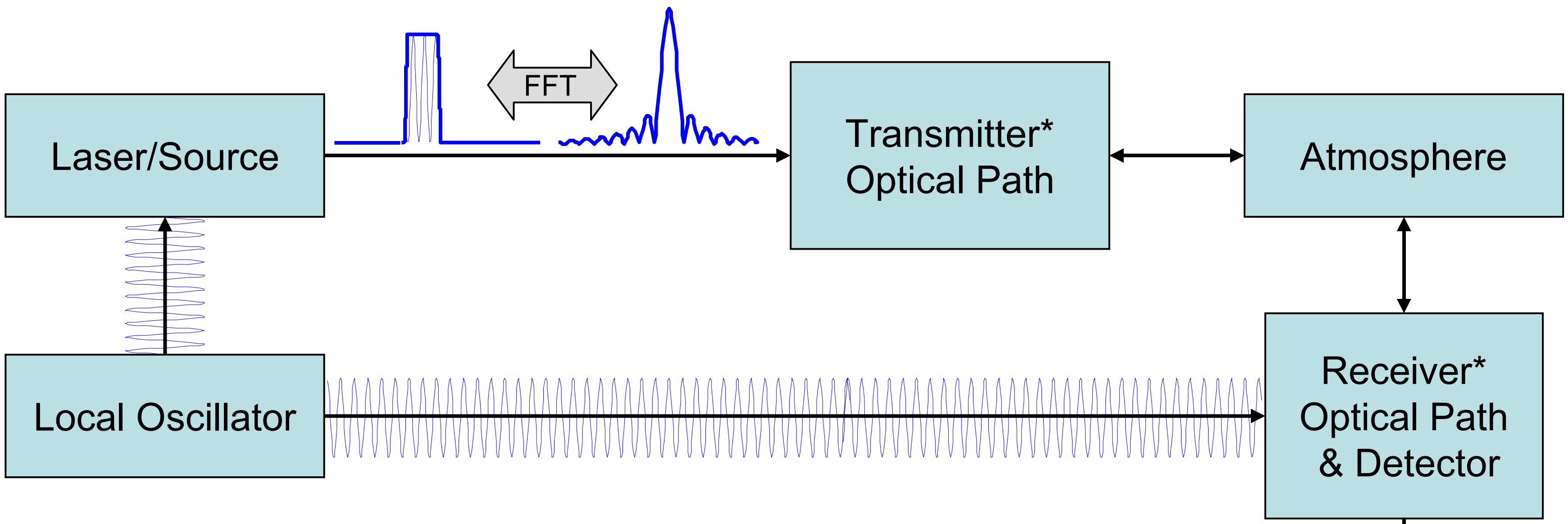
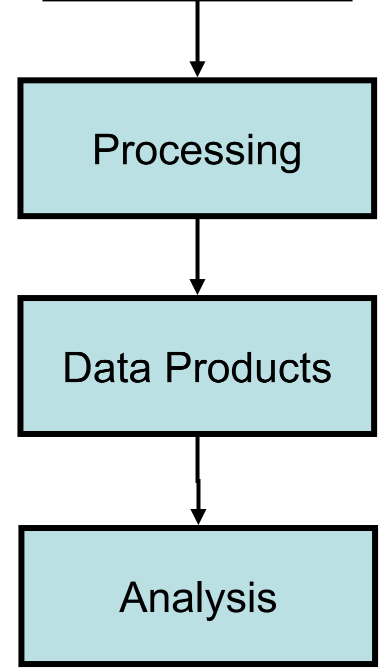
Coherent Doppler Lidar





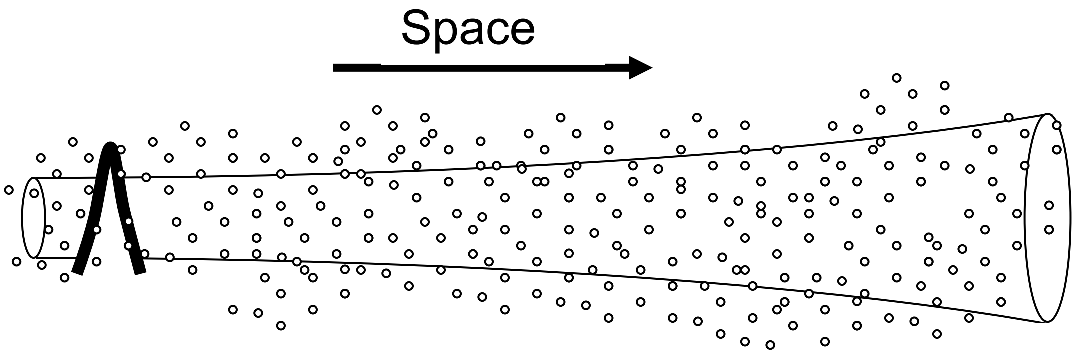
In coherent Doppler lidar we send pulses of light out to interact with aerosols in the atmosphere. If the aerosols are moving with respect to the light source (i.e. due to wind) then the scattered light will have experienced a Doppler shift. The goal is to measure this Doppler shift and turn it into a velocity product.

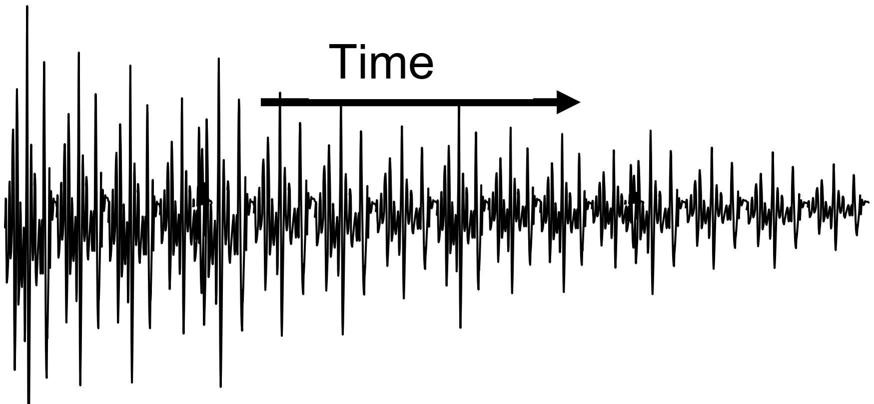
* Transmitter & receiver paths usually share common optics

- Coherent Detection
- Laser
- Local Oscillator + shift
- Transmit/Receive paths
- Atmosphere
- **Detection & Processing**
- Analysis and Data products
- Field Work

Return signal processing

- Return signal mixes with local-oscillator creating the beat frequency + offset signal. $f_{\text{detected}} = f_a - f_{LO} = f_{Dopp} + f_{offset}$
- This beat signal is optically detected, analog filtered, demodulated, and sampled… but not necessarily in that order.





Return signal processing

- This beat signal is optically detected and then…
  - Analog filtered
  - Demodulated (analog or digital)
  - Sampled (one or two channels)

…but not necessarily in that order.

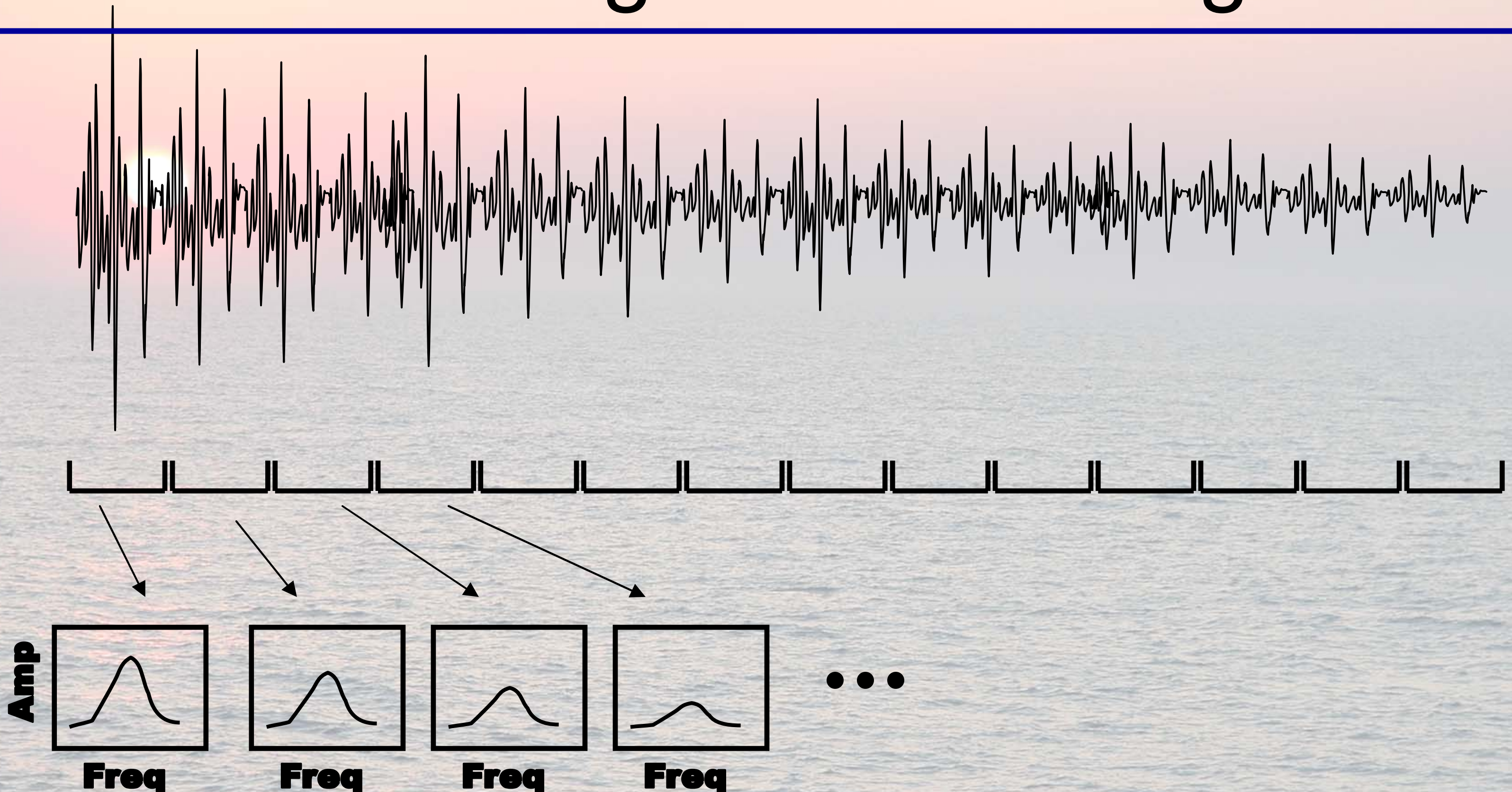
HRDL

- Complex analog demodulation
- Analog filtering (2 channels)
- Sampling – (2 channels)

MOPA

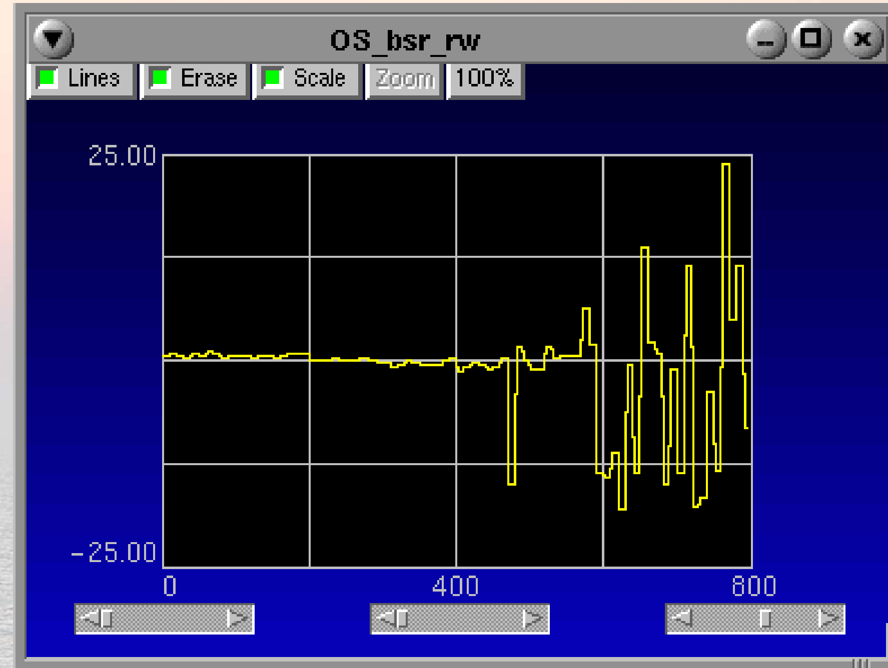
- Analog Filtering
- Sampling
- Digital demodulation

Return Signal Processing



- Break into gates (equal to laser pulse length)
- Find spectrum for each gate
- Average spectra for same range gate from different pulses
- Find frequency peak for each gate to find Doppler shift and intensity as a function of range

Example Data



Velocity (m/s)

Single beam range resolved estimates: 150m / 2X sec

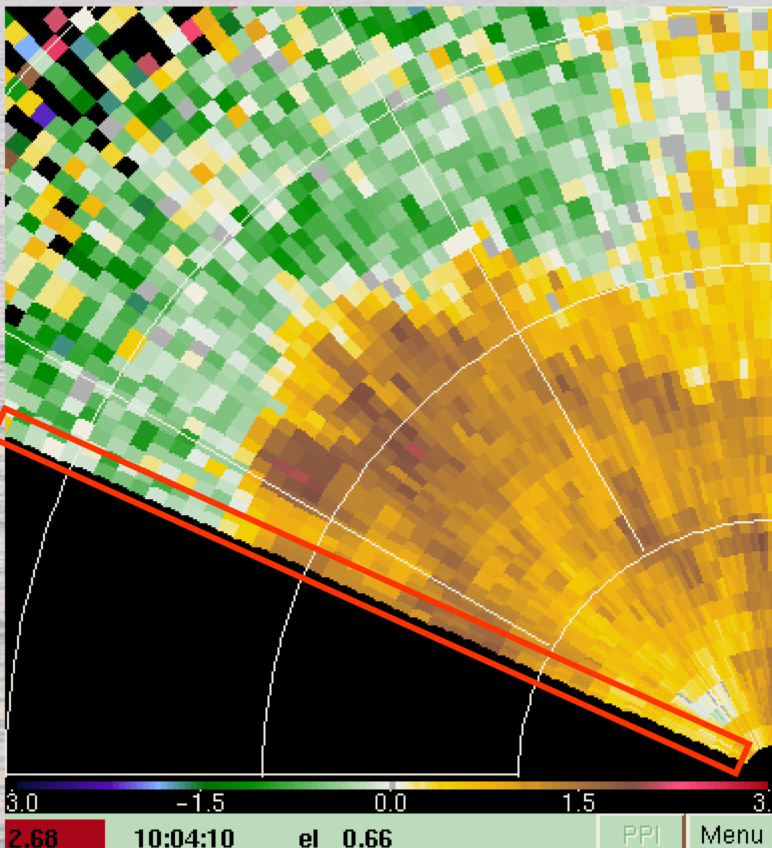
Signal Strength (dB)

12 km max range

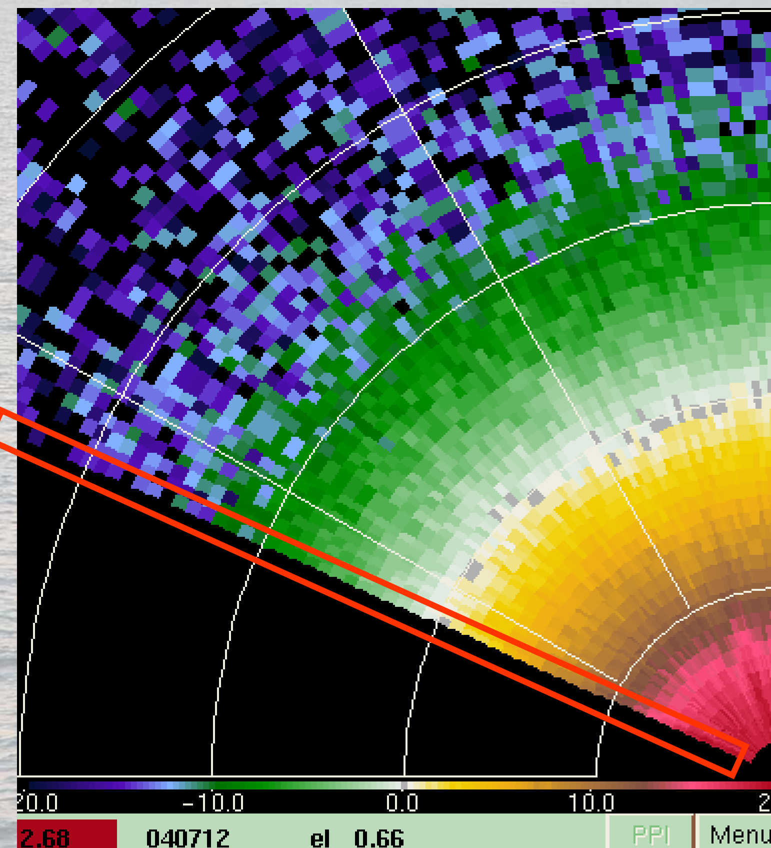
Example Data

Color code and combine single beam results into scanning display

Velocity (m/s)

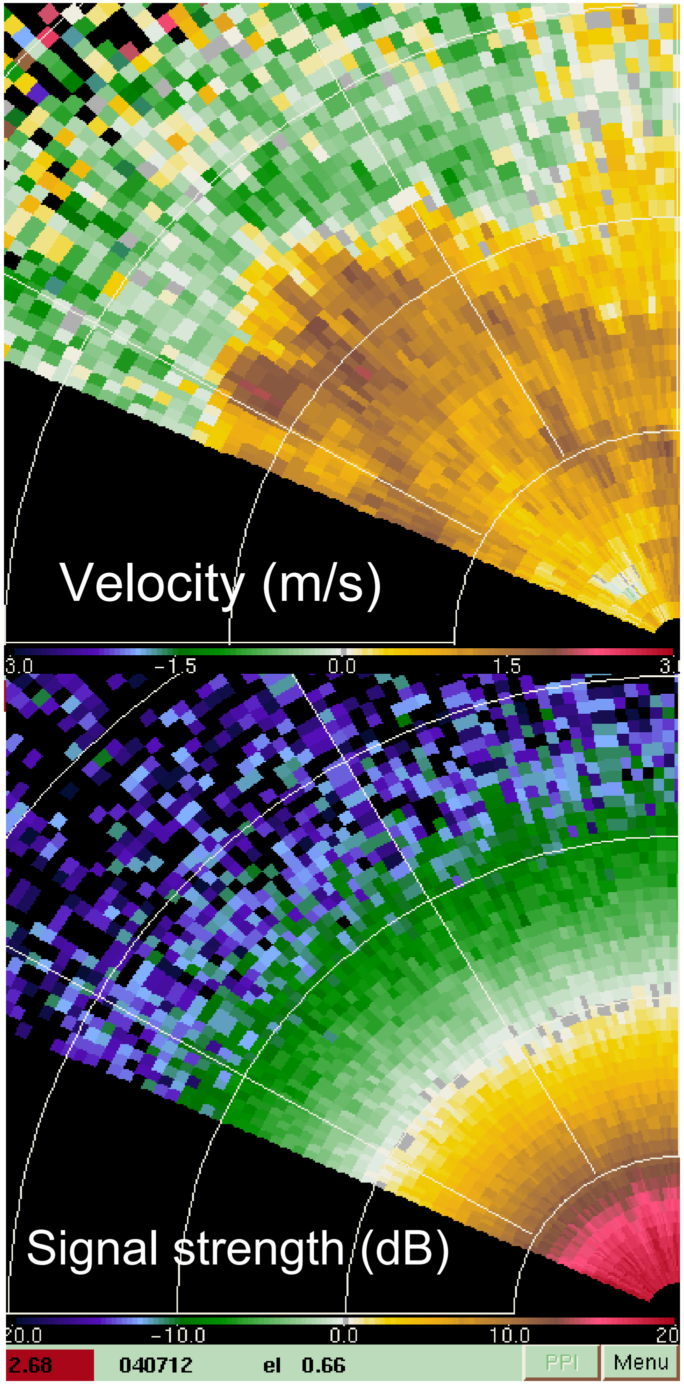


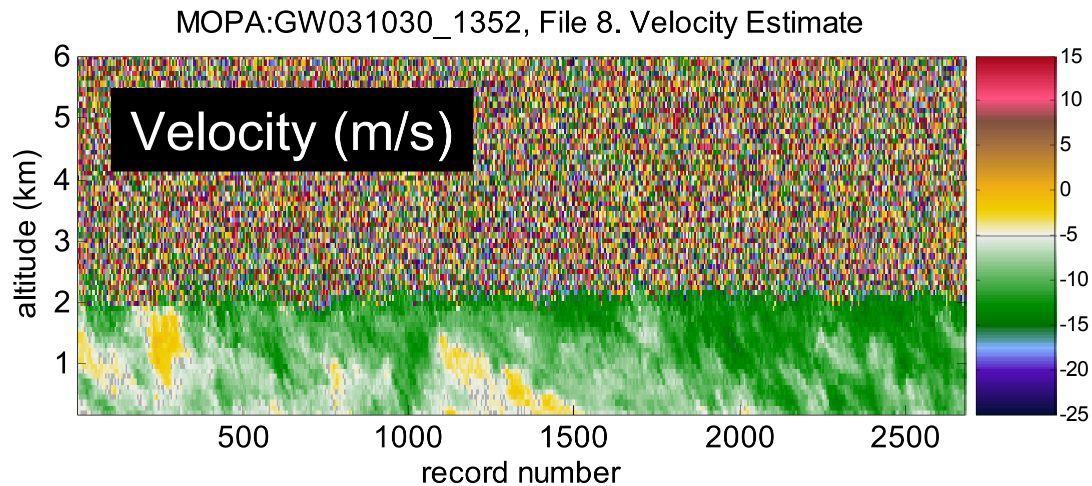
Signal strength (dB)

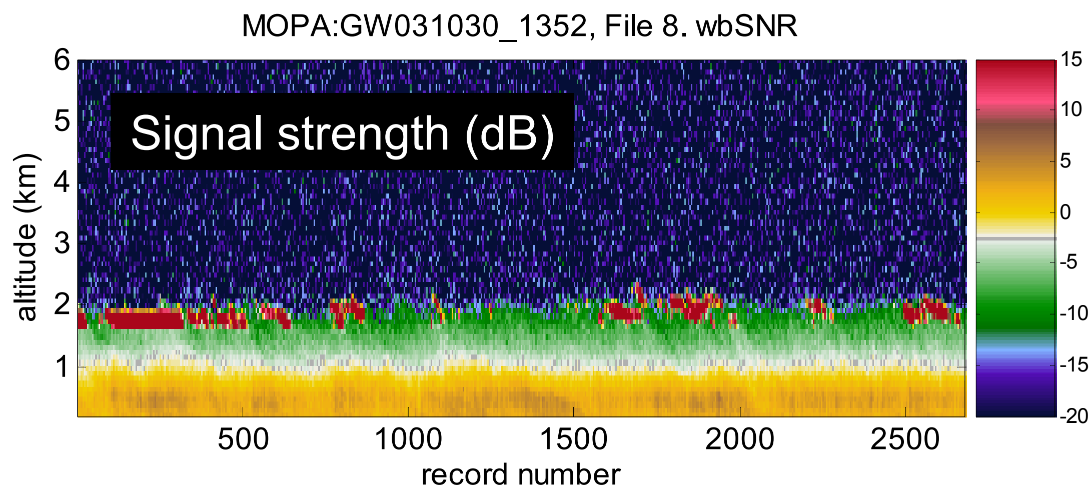


Doppler lidar data displays

- Depend on scan type
- versus range or altitude
- colormap: Cool = toward the lidar
  Warm = away from the lidar







Signal Processing: Real Data Example

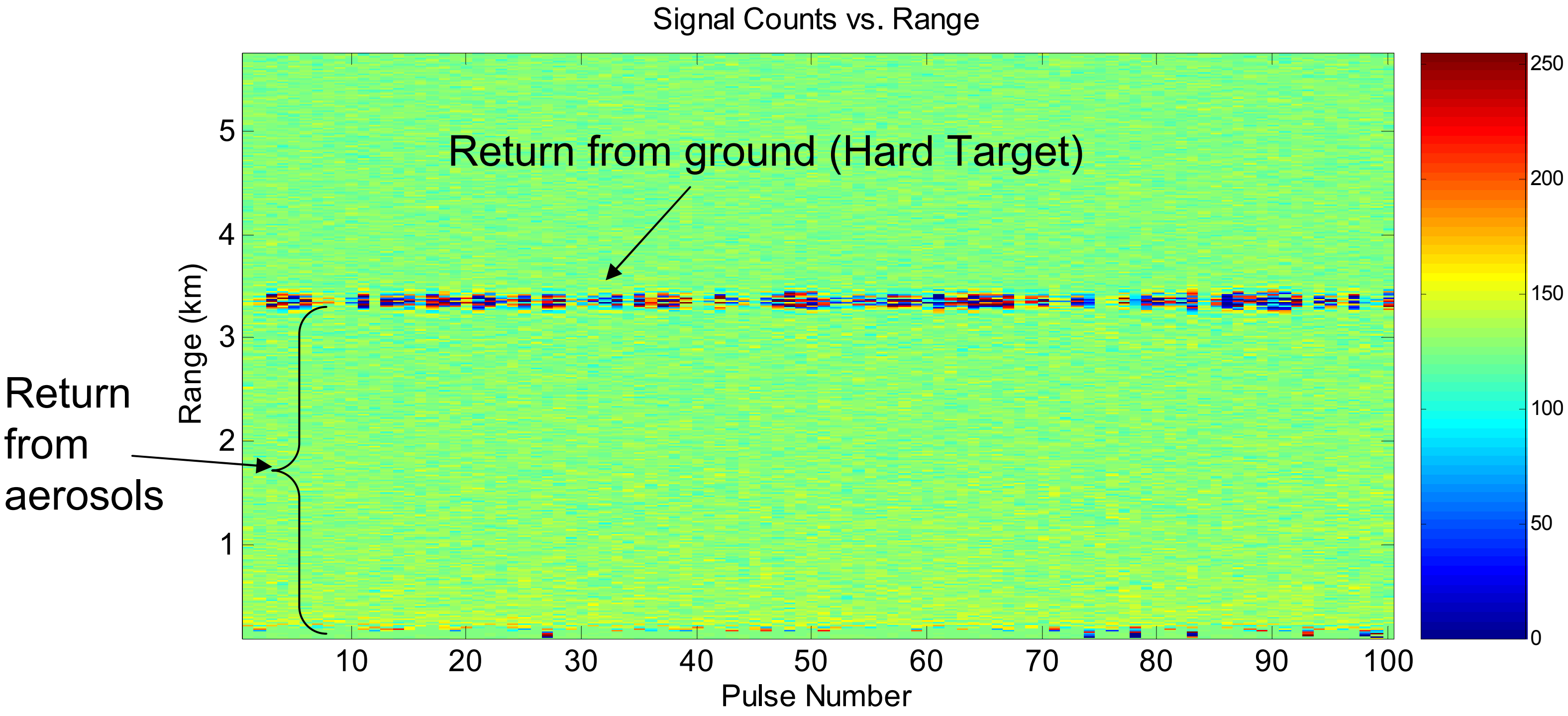
This data comes from an instrument called the Twin Otter Doppler Wind Lidar (TODWL). It flies in an aircraft and points down at the earth.

The figure below contains a visual plot of the raw data (3900 samples per pulse) signal counts vs. range and pulse #.

Range for this plot (and all other plots we'll show here) is line-of-sight (LOS) range.

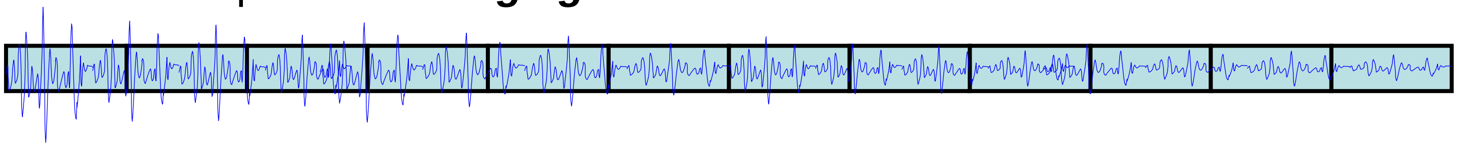
Goal: Calculate velocity and CNR versus range for this data set.

TODWL Parameters	Value
Wavelength	2.05 microns
Energy/pulse	5 mJ
Receiver Aperture Diameter	9 cm
PRF	80 Hz
Sampling Rate	100 MHz
Search bandwidth	50 MHz
Points per gate	64
Gate Width	96 meters
# pts in FFT	256
# bins in signal BW	11 = 4.3 MHz
# bins in search BW	128 = 50 MHz

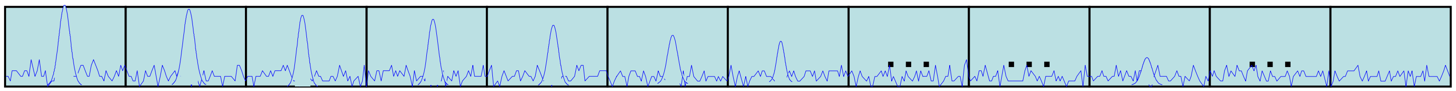


Return Signal Processing: Steps for processing example data

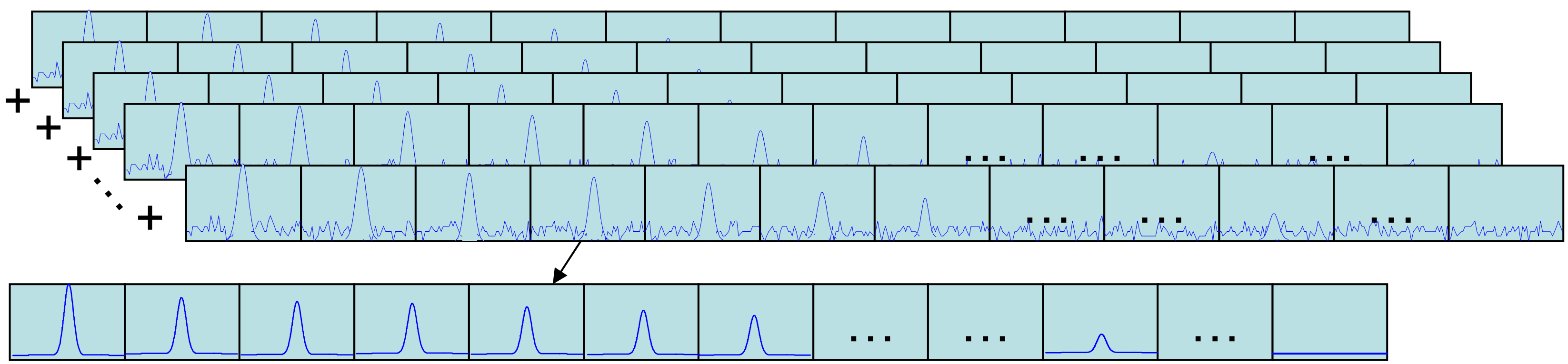
1. Divide each pulse into ***range gates***



2. Find the ***spectrum*** for each range gate of each pulse. (Spectrum is the squared magnitude of the FT of the data – not just the FT)



3. ***Average*** the spectrum for each range gate, with the spectra from the same range gate in all the other N pulses



4. The frequency axis should be 0 to 50 MHz.

5. Find the ***peak*** in the spectrum at each range gate. This gives the measured frequency. Find the offset from the center by subtracting 25 MHz to get the Doppler induced offset Δf.

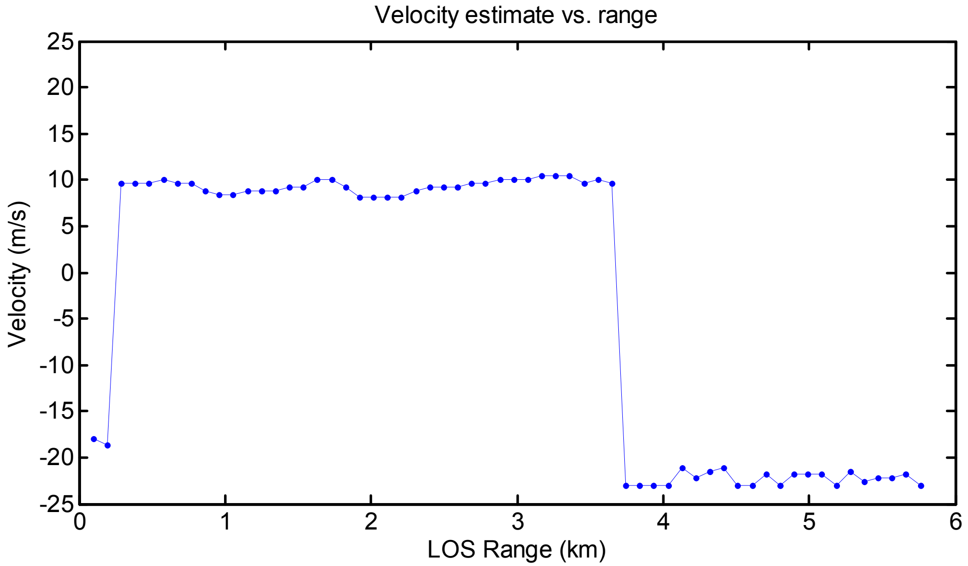
Return Signal Processing: Steps for processing example data

Recall that the ***frequency shift*** corresponding to the LOS wind is given by

$$\Delta f = \frac{2v}{\lambda}$$

So, the ***velocity*** corresponding to the peak frequency is given by:

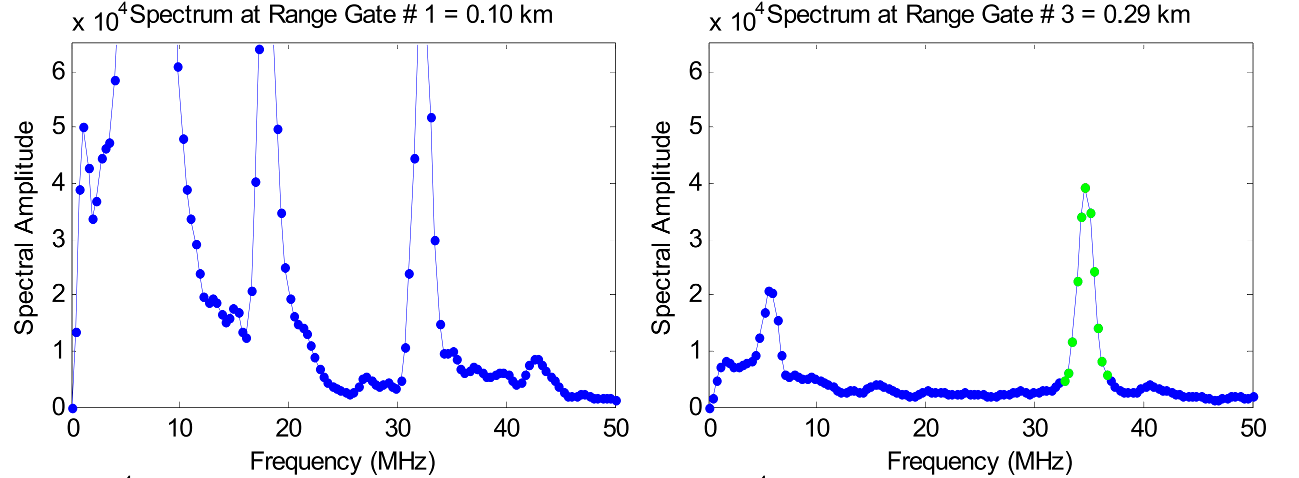
$$v = \frac{\Delta f \lambda}{2}$$

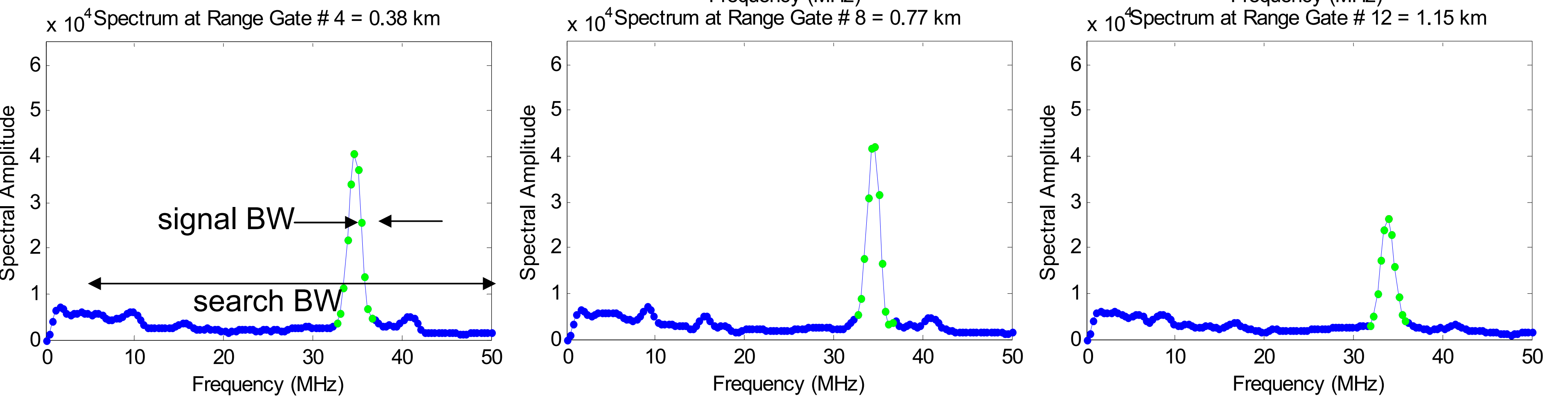


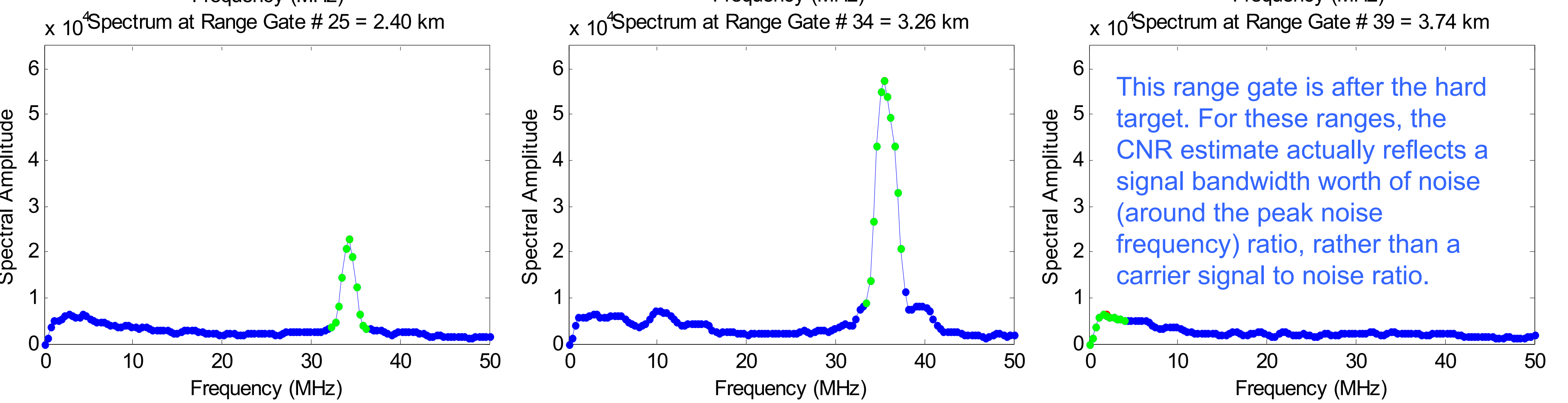
Questions related to processing

- What happens to the bandwidth when the range gate is shortened/lengthened?
- Why can't the range gate be shorter than the pulse length?
- What happens to the noise floor when you average the spectra?
- What happens to the velocity estimates if you average only 10 pulses worth of spectra per beam? How about 100?
- Does the peak intensity value change much when you average the spectra?
- Notice that the noise floor in this example is not flat (white). How does this affect the velocity estimates when there is no return signal? Estimate this noise floor shape.

Processing example data: Averaged spectra for different range gates

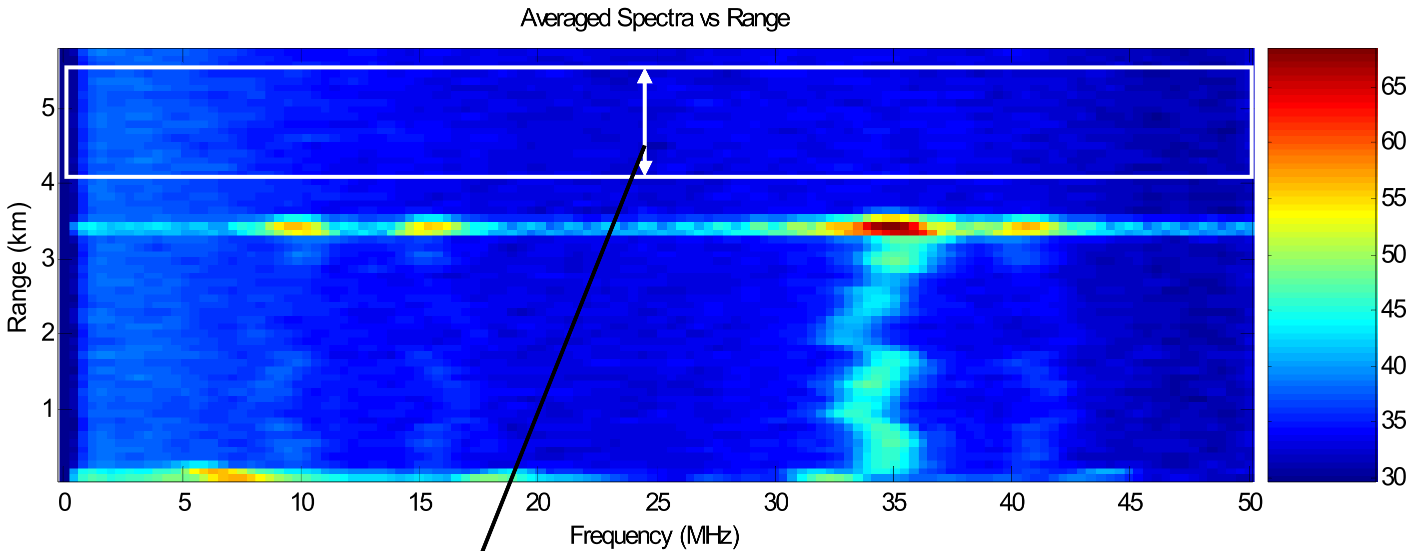




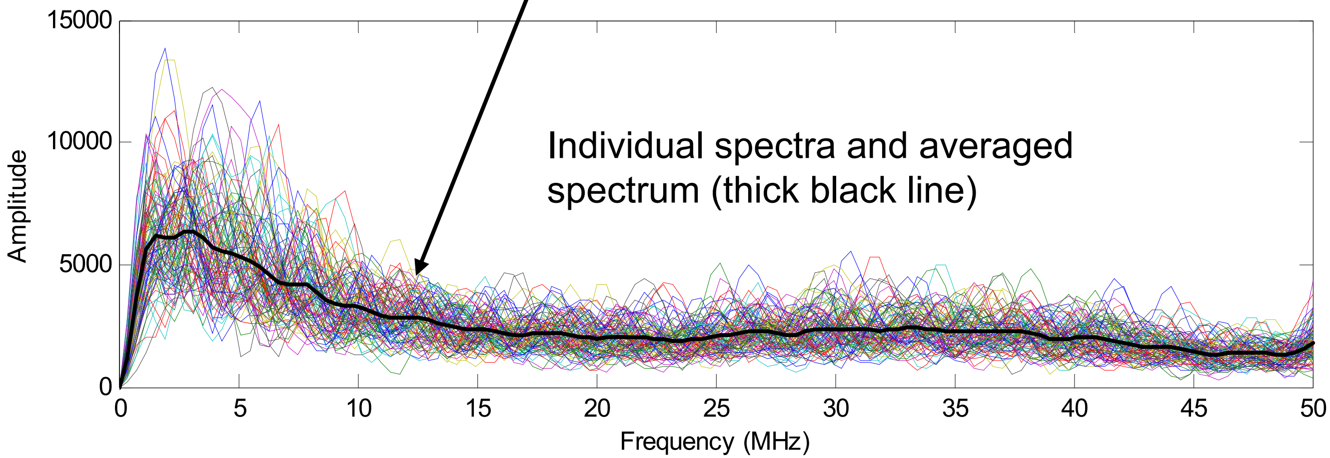


Return Signal Processing: Processing example data – Noise floor whitening

Notice the increased signal levels in lower frequencies. We need to flatten/whiten the noise floor.

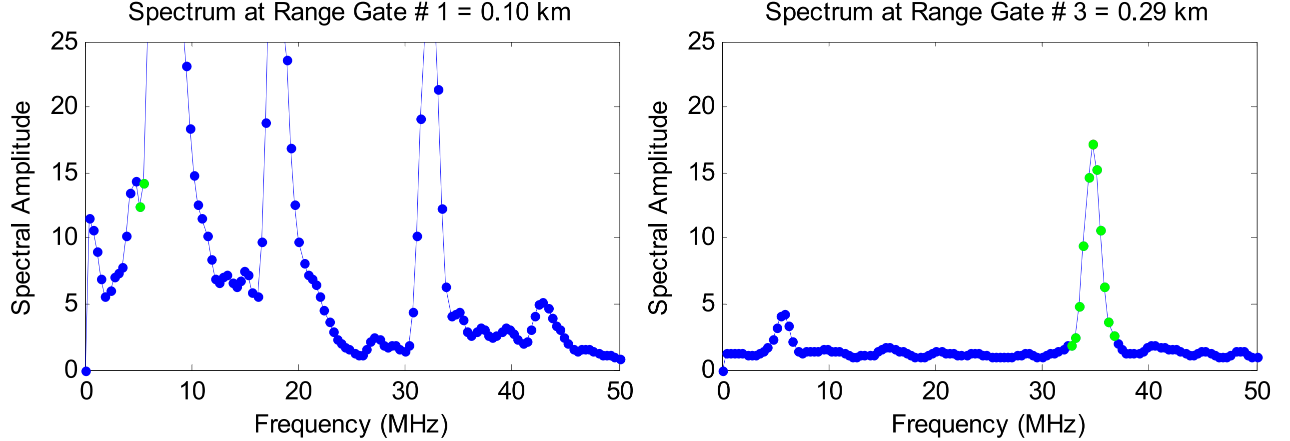


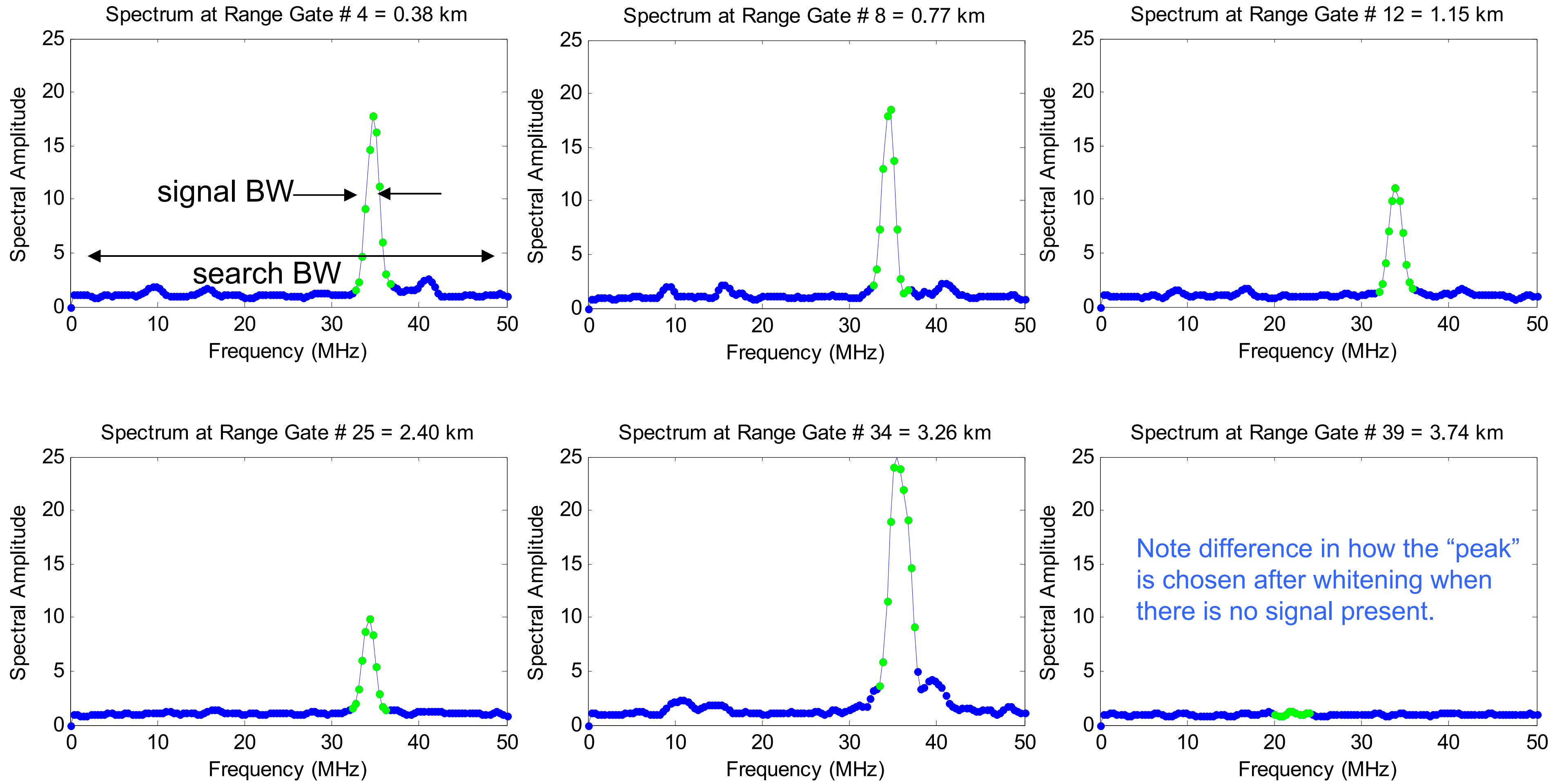
Find the average spectrum in an area where there is no return signal. This is the estimated spectral noise floor



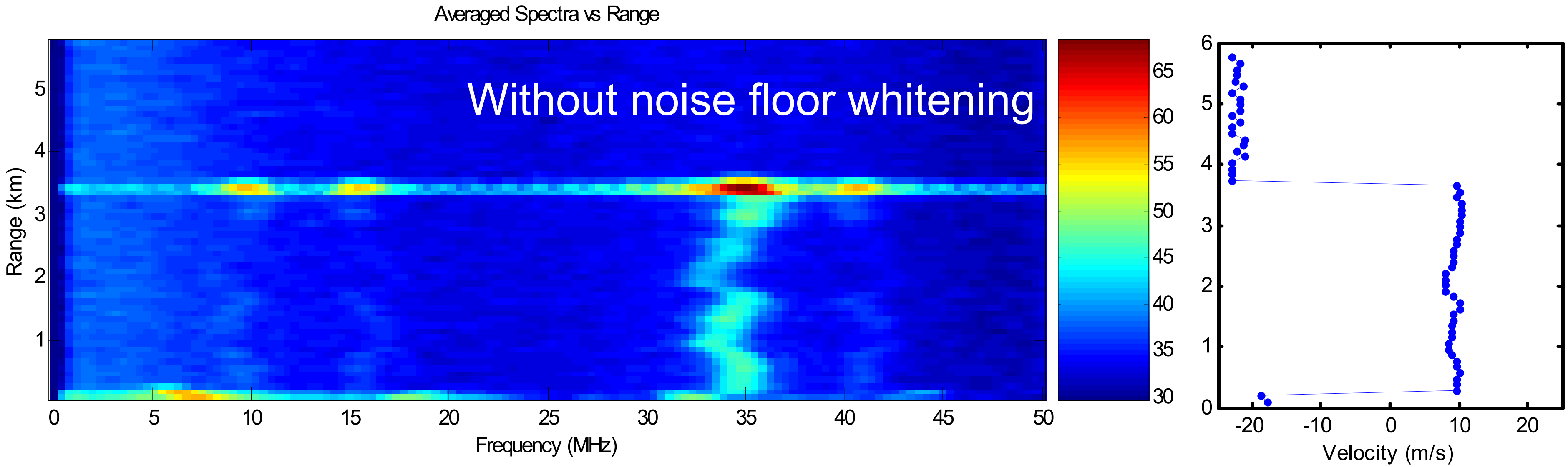
Then divide all of the other spectra by this noise floor estimate before estimating the peak frequency.

Processing example data: *Whitened* & Averaged spectra for different range gates

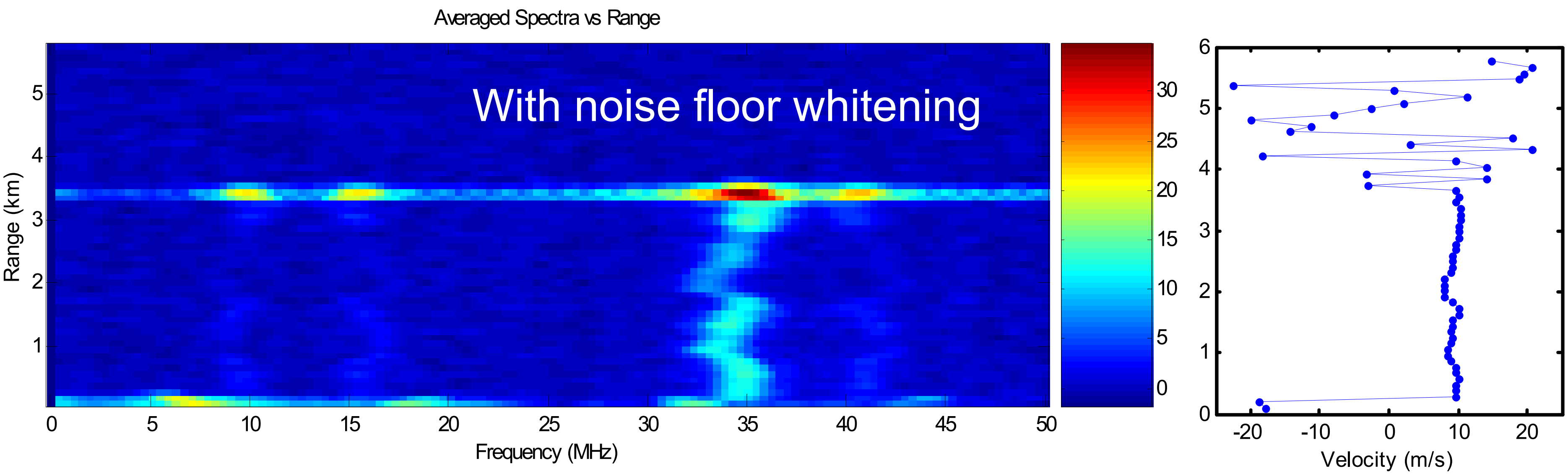




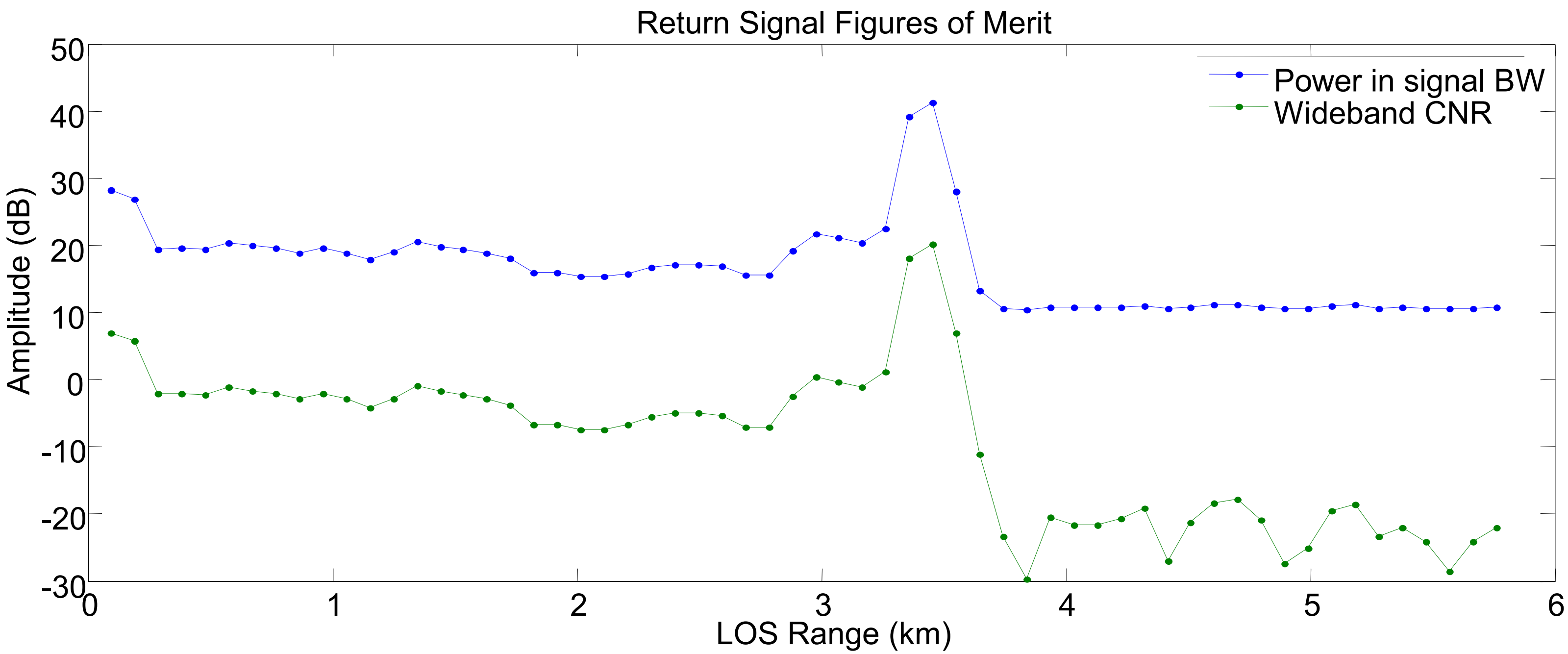
Return Signal Processing: Processing example data – noise floor whitening



Note that when the noise floor is not flat, then velocity estimates in areas of low signal will be biased toward the noise floor peaks.



Return Signal Processing: Processing example data (CNR)



To calculate CNR of real data, first sum the values in the frequency bins within the signal bandwidth (+/- 5 bins from the peak frequency) of the spectrum for the given range gate.

$$P_{f_{sig}} = \sum_{k \in SignalBW} f_{sig}(k)$$

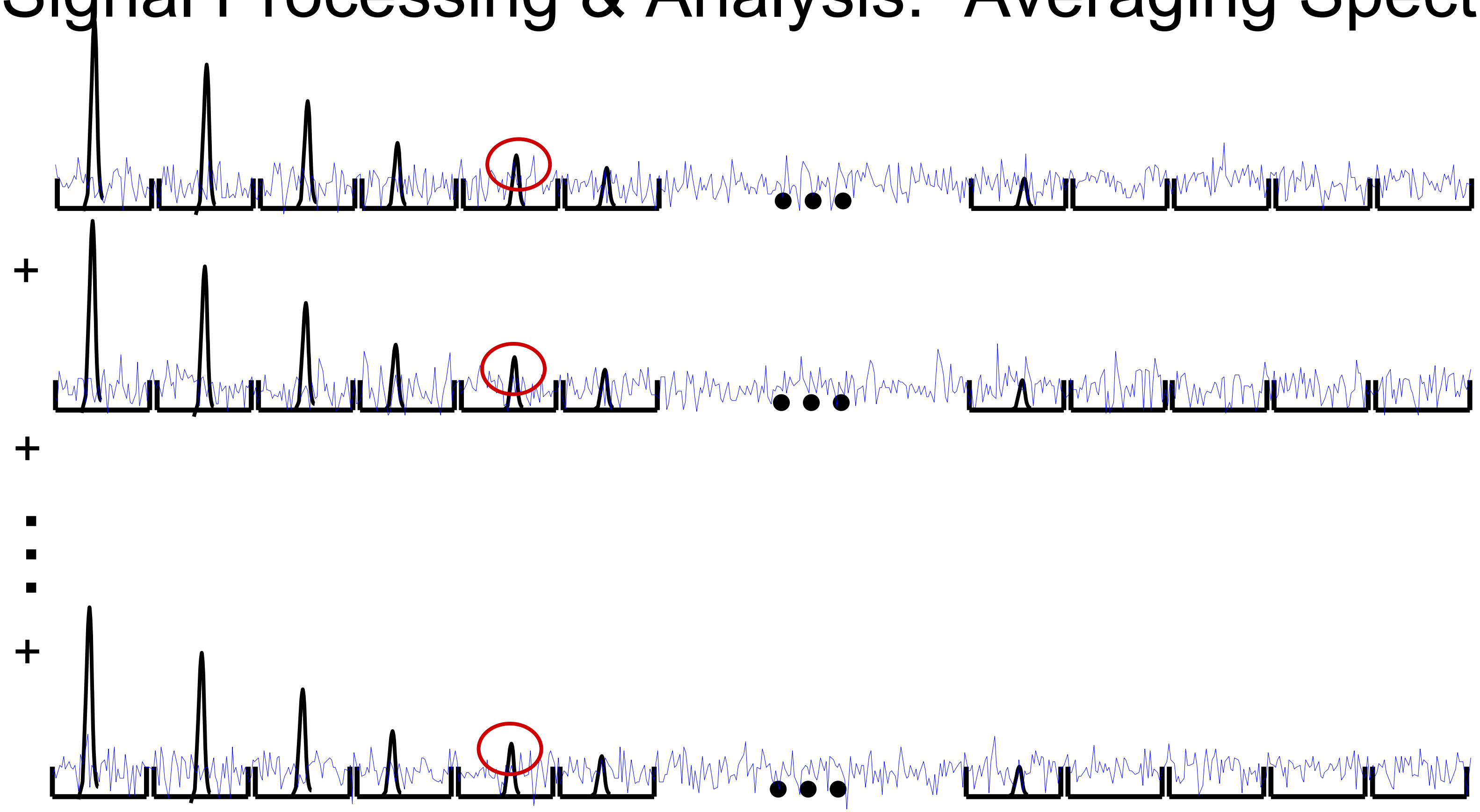
The Wideband CNR is then calculated as follows:

$$CNR_{wb} = \frac{P_{f_{sig}} - N_{sigBW} P_{ns}}{N_{wb} P_{ns}}$$

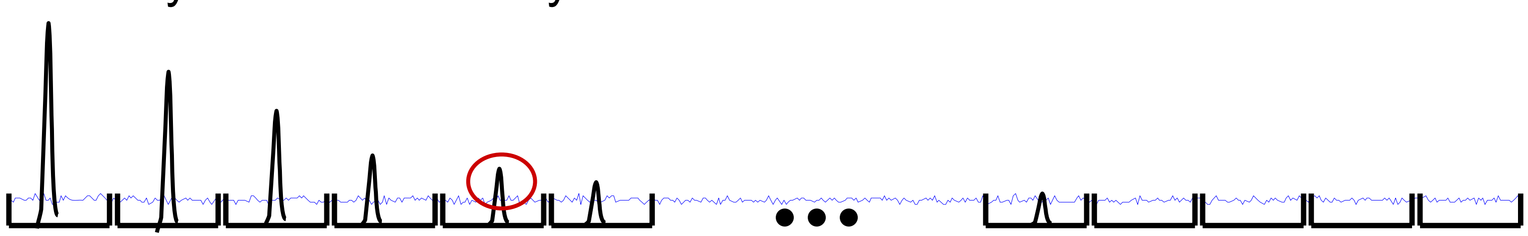
Where P_{ns} is the average noise power, N_{sigBW} is the number of bins in the signal bandwidth and N_{wb} is the number of bins in the spectrum (N_{wb} = NFFT/2 = 128). The N_{wb}/NFFT/2 is equivalent to the signal BW to total search BW ratio.

- Coherent Detection
- Laser
- Local Oscillator + shift
- Transmit path
- Atmosphere
- Receiver/Detection
- Processing
- **Analysis and Data products**
- Field Work

Signal Processing & Analysis: Averaging Spectra

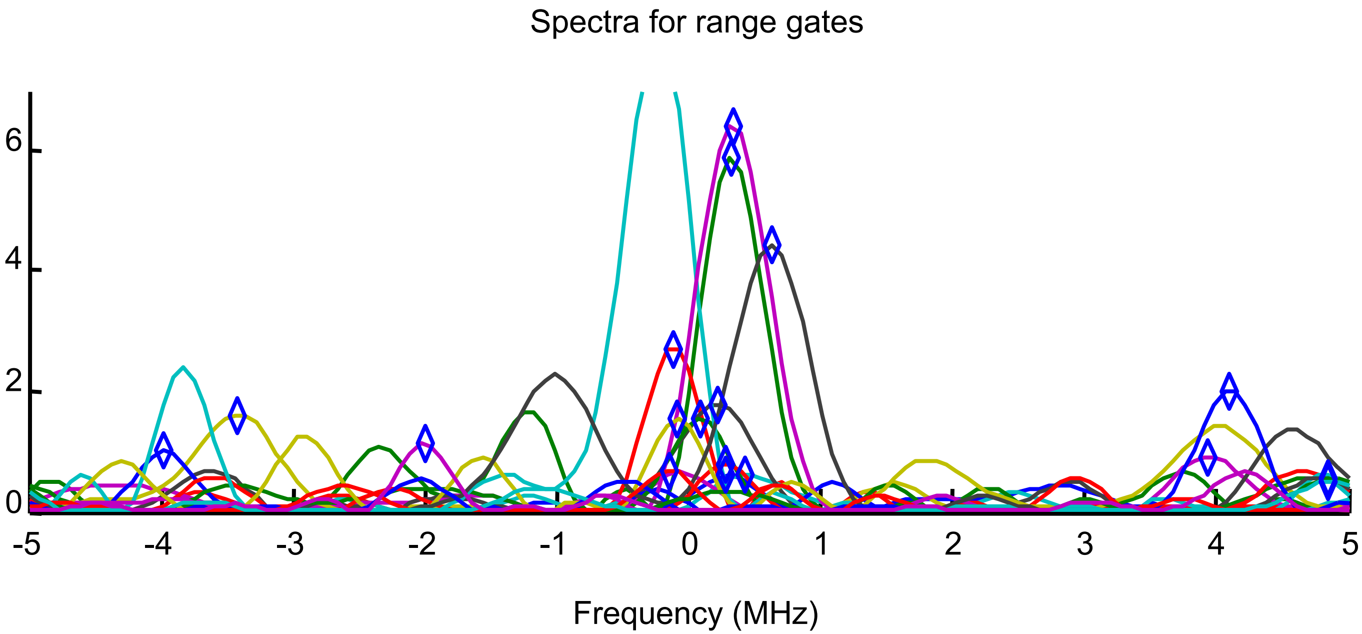


- Average the spectra and THEN estimate the frequency/velocity
- Why not the other way around?

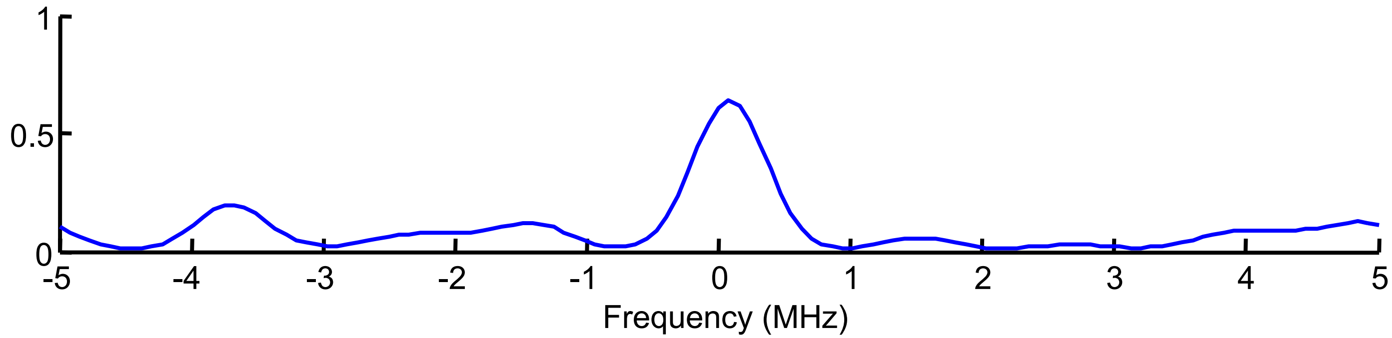


Signal Processing & Analysis: Averaging Spectra

Individual noisy spectra

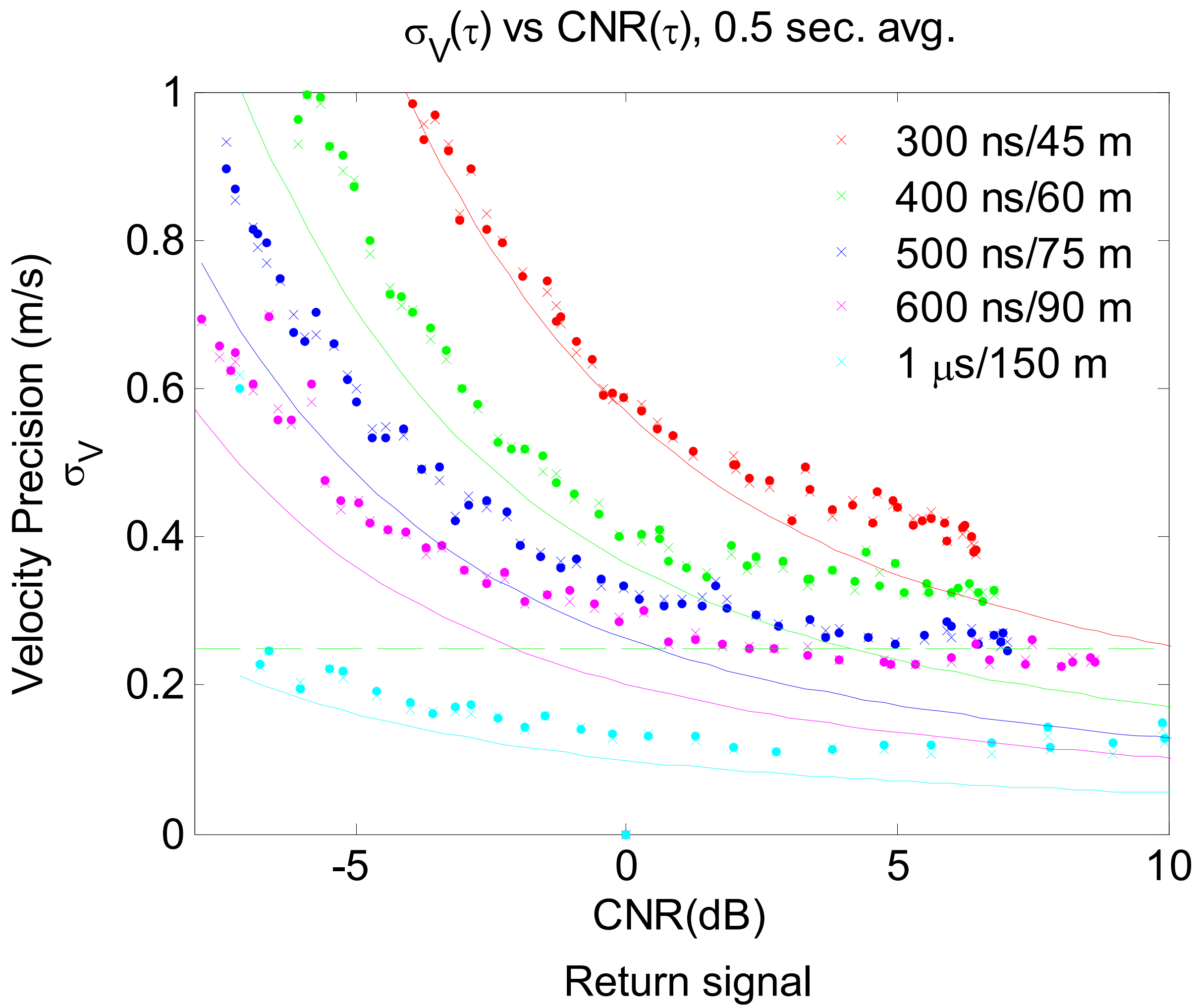


Average of all spectra



Result: Average CNR does NOT change
-but velocity estimate *precision* improves

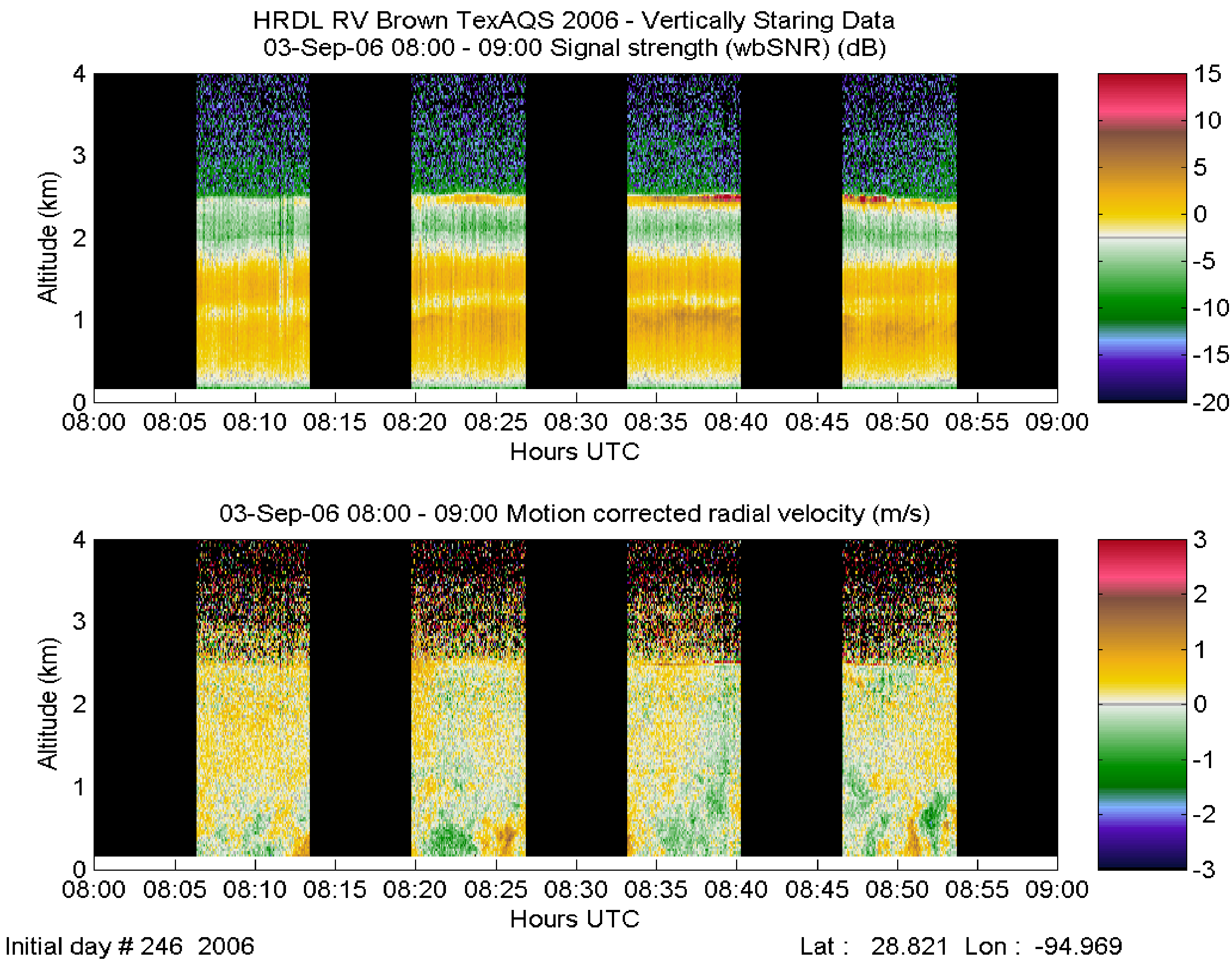
Velocity precision vs CNR and various pulse widths from mini-MOPA



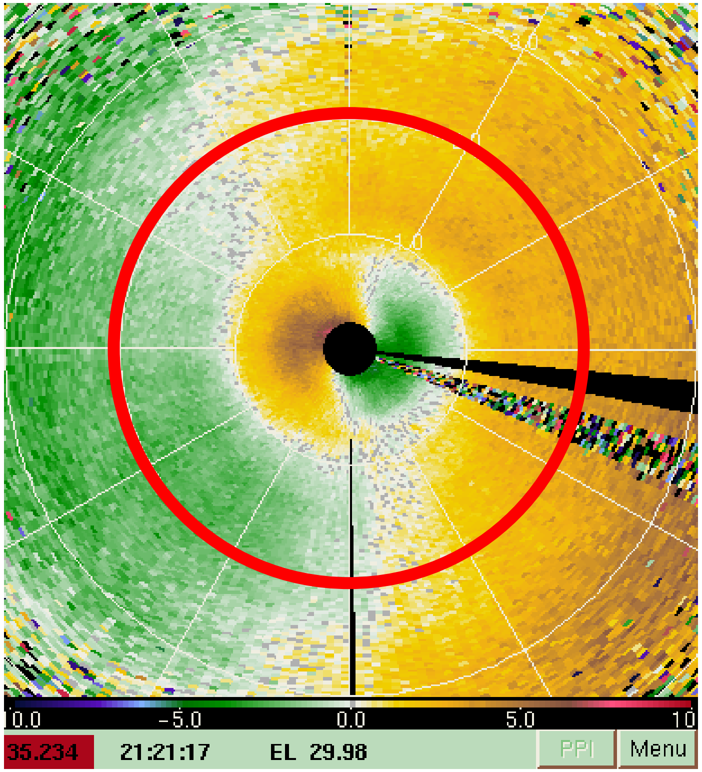
Tradeoffs between:

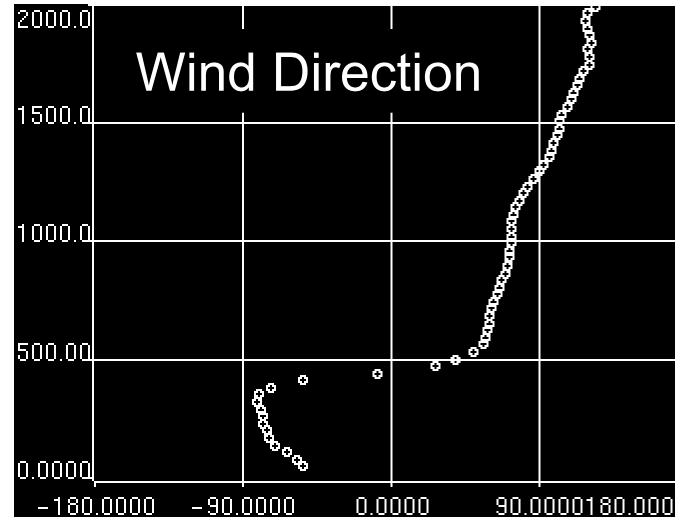
- detection bandwidth and CNR
- range gate length (range precision)
- velocity precision
- time resolution

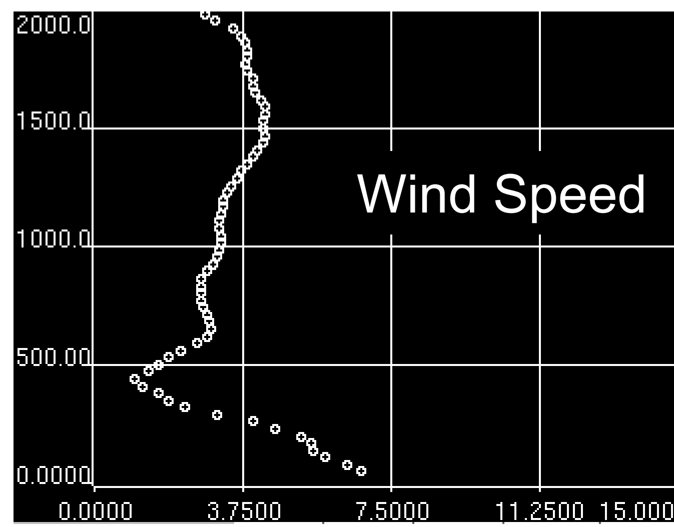
Doppler Lidars: Observations of Mixing and Layering

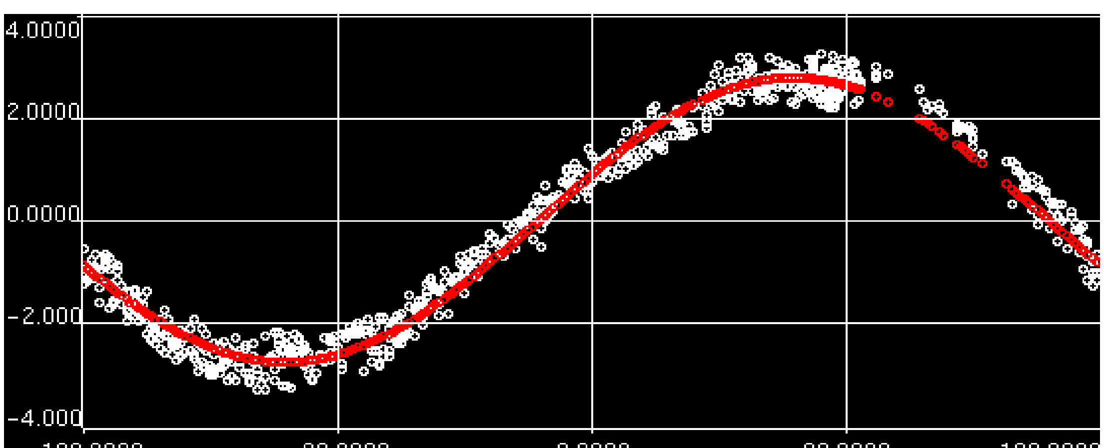


Doppler Lidars: Calculating wind profile from PPI scans



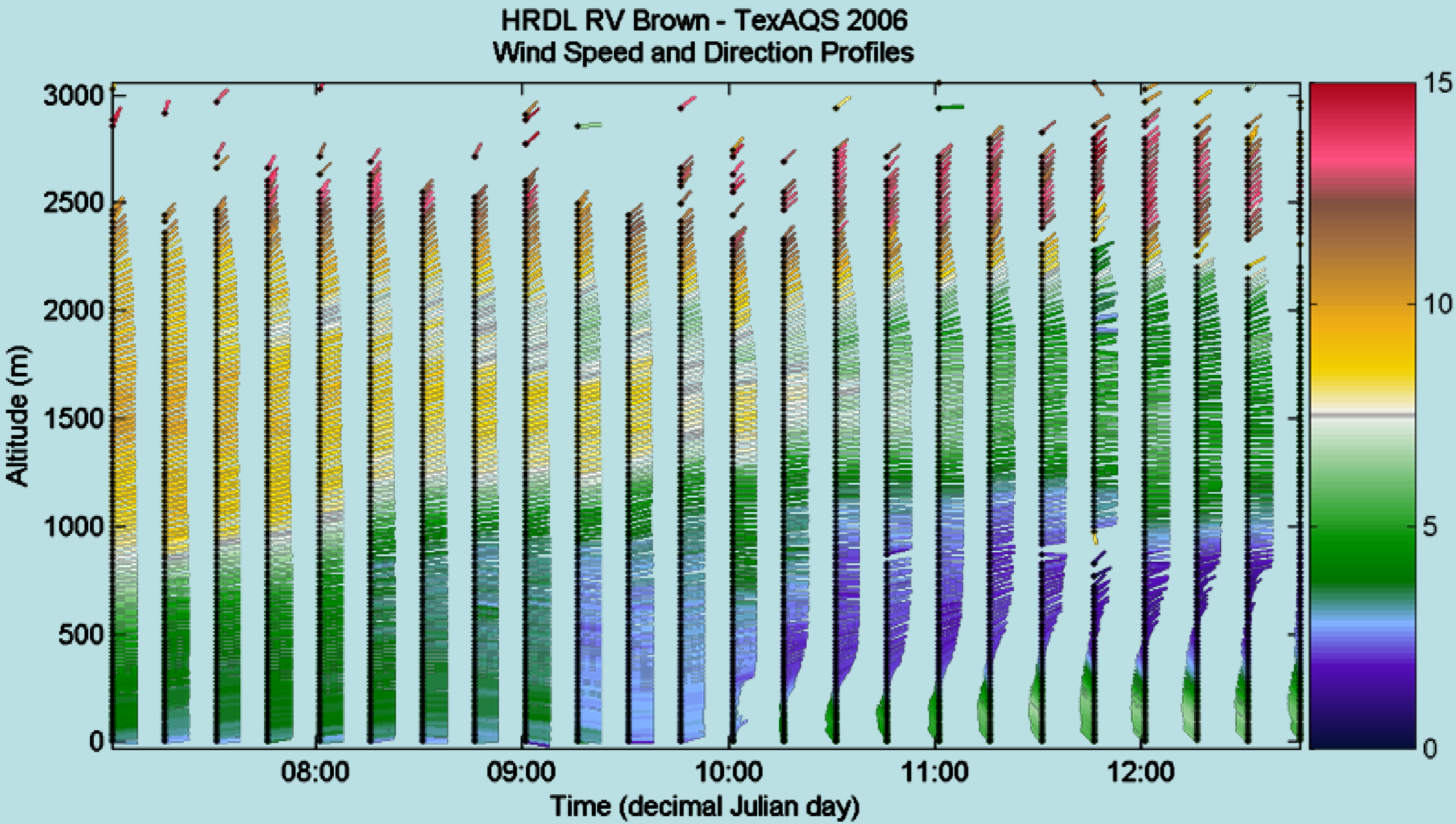






Wind Profiles

- The dot is “now” (profile time).
- Wind us coming *from* the direction corresponding to the line angle.
- Color indicates wind speed according to the colorbar.



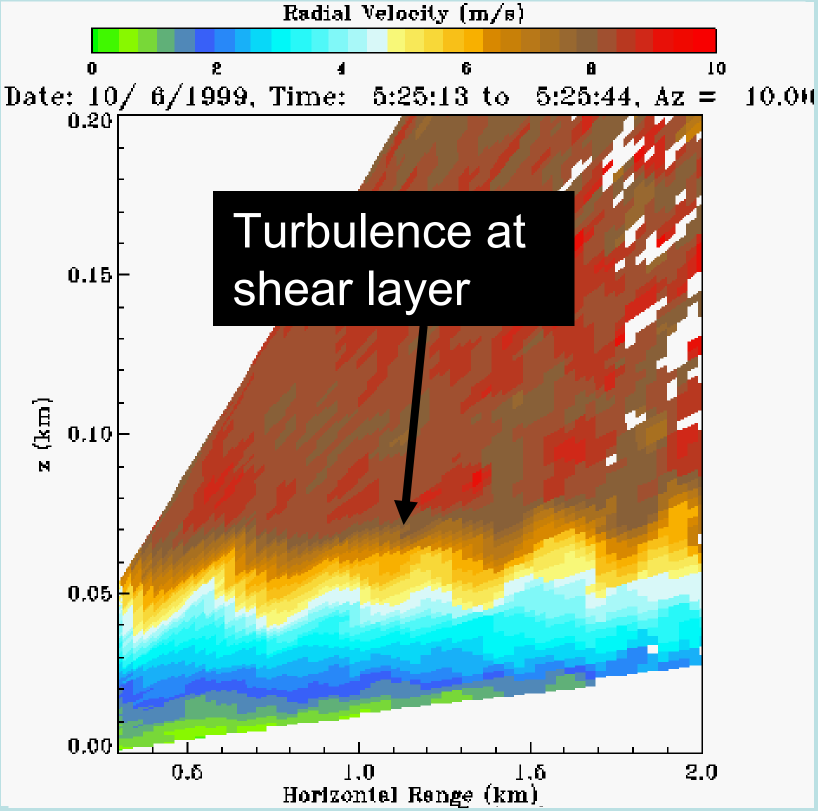
Wind Profiles: Info

- Down to 5 m above the surface/water – variable separation increasing with altitude to 30 m.
- Precision for wind speed estimates
  - LOS estimates < 20 cm/s
  - Profiles – depends on turbulence, usually better than LOS estimates.
- Precision for wind direction: usually depends on wind speed.

Wind Profiles: Uses

- Observation of
  - sea-breeze/land-breeze conditions,
  - low level jet
  - shear & mixing
  - diurnal cycles
- Help in understanding changes in atmospheric conditions
- Previously sheared layers started mixing down. From which direction did the stuff in that layer come?
- Diurnal cycles: patterns in wind speed and direction at all altitudes

Turbulence Measurements



Objectives

- Profiles of turbulence
- Study mixing process
- Parameterization of sub scale processes for model improvement

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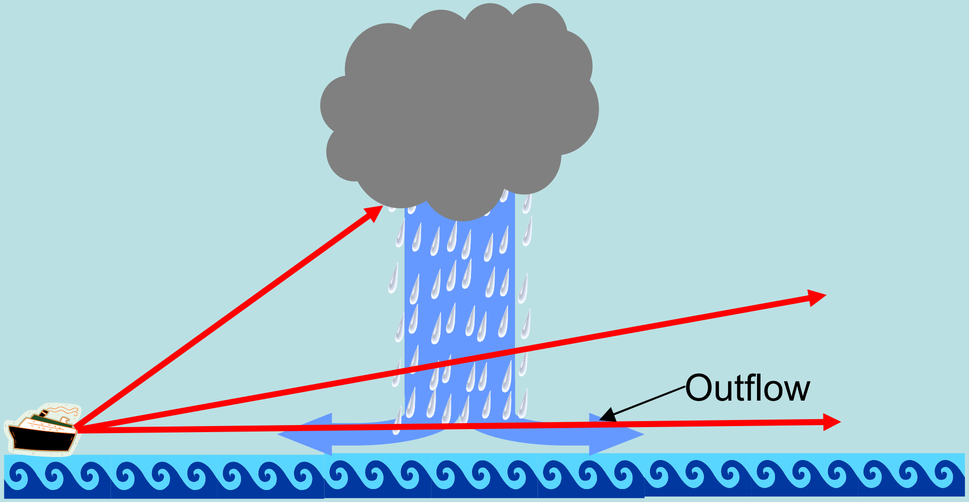
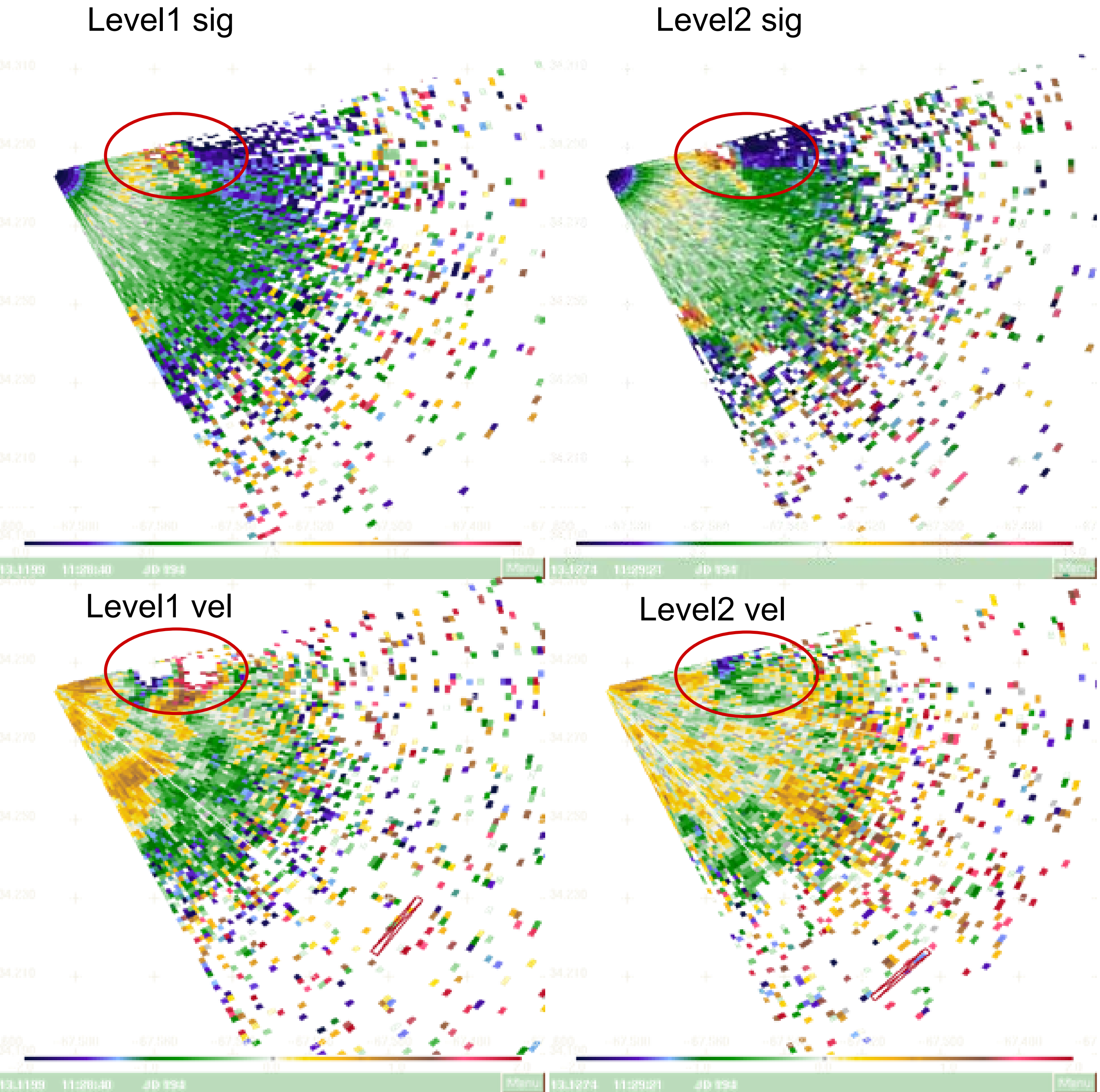
Observations of thunderstorm outflows





Frame 8

11:28:40

- Coherent Detection
- Laser
- Local Oscillator + shift
- Transmit path
- Atmosphere
- Receiver/Detection
- Processing
- Analysis and Data Products
- Field Work

What does the NOAA/CSD/Optical Remote Sensing Group do ?

- Investigate and implement new technology for improving observations of the atmosphere and ocean
- Demonstrate and apply new measurement techniques for:
  - Air quality
    - Chemical distribution
    - Dynamics for mixing/transport
  - Improving and assessing weather forecast model performance
    - Parameterization of sub grid scale processes (turbulent mixing, complex terrain)
    - Providing new observations for data assimilation.
    - Cal/val forecast models
  - Understanding climate forcing mechanisms
    - Clouds / aerosol indirect effect on climate
    - Sources and sinks of important species (CO2, O3, H20)
    - Ocean / atmosphere energy exchange

Basic Lidar measurements

- Chemical distributions (ozone, water vapor, NH3, CO_2)
- Cloud properties
- Aerosol measurements
- Low level mean winds
- Residual winds
- Turbulence, general dynamics

Instruments have been mounted on research ships for sea based operation

Challenges include:

- Sea salt corrosive environment
- High vibration
- Platform motion & orientation
- Low frequency accelerations – stability issues
- Big waves and leaky seatainers