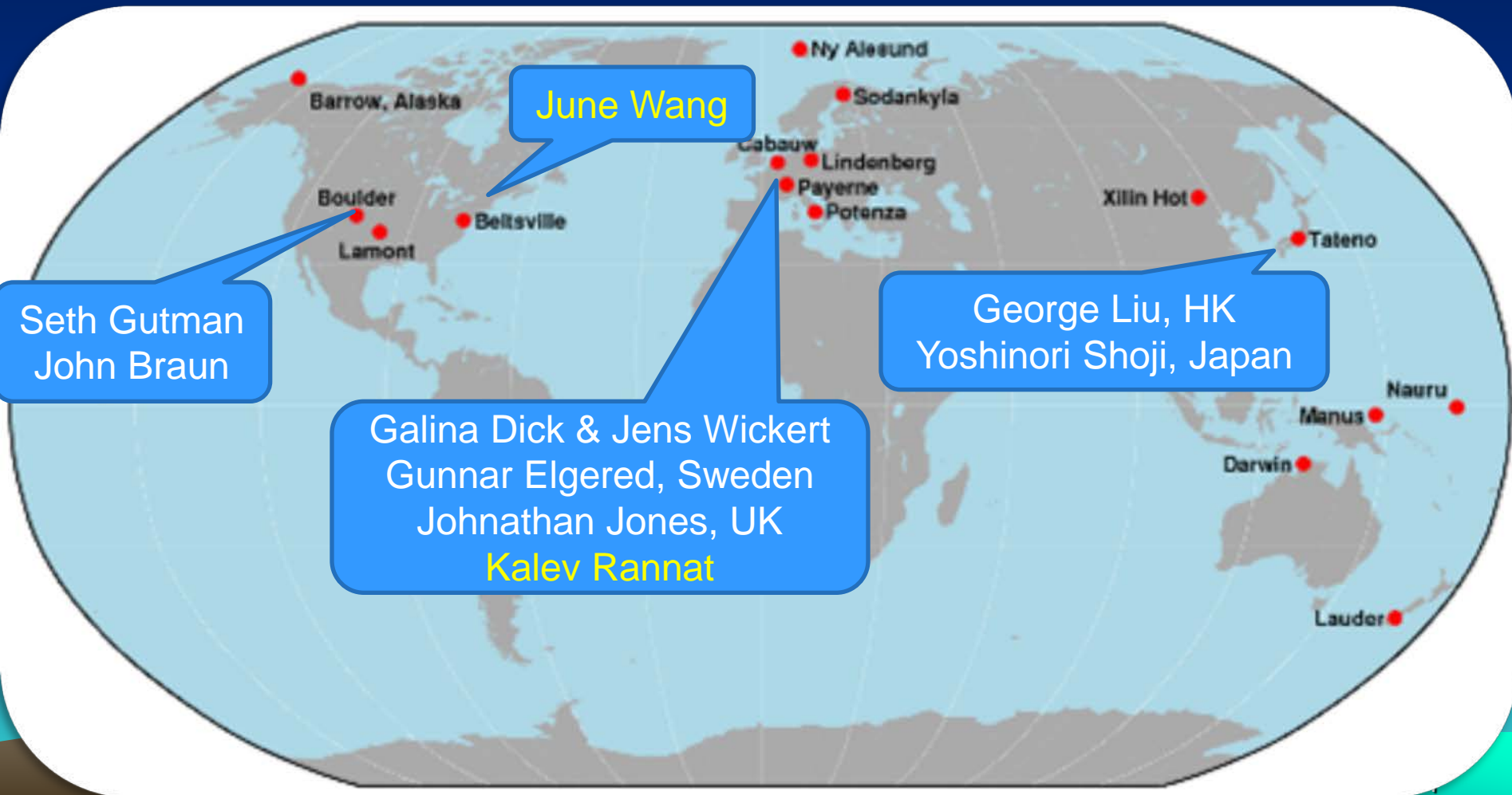


GRUAN GNSS Precipitable Water (GNSS-PW) Task Team:

10 members from 7 countries



1. Guidelines: 8 Tasks

2. Implementation:

- *GNSS Data Central Processing (GFZ)*
- *GNSS Data Flow (Kalev)*

3. Research:

- *Co-locations*
- *Long-term stability*

4. Future of TT

How does GNSS estimate precipitable water?

Total delay = Ionosphere + dry + wet

IONOSPHERE

The ionosphere delay is (inversely) proportional to the frequency of the radio-waves. Thus the delay can be calculated by measuring the difference in the travel times for the two frequencies

The refraction (slowing) of the GPS signal as it passes through the atmosphere alternatively be viewed as increase in path length: called the "path delay" and with units of distance

TROPOSPHERE

The troposphere slows both GPS frequencies equally. This means the tropospheric delay must be modeled as a free parameter in the GPS processing

Meteorological data (P_s , T_s) & estimated T_m

Dual-frequency GNSS mea.:
GNSS Ephemeris
Station position
Timing

Forward model

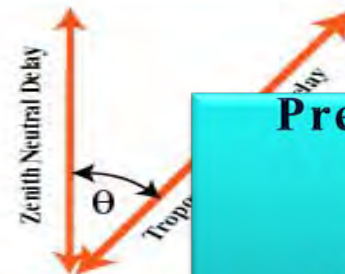
Atmospheric delay
($ZTD = ZHD + ZWD$)

Precipitable Water (PW)

$$ZWD = ZTD - ZHD$$

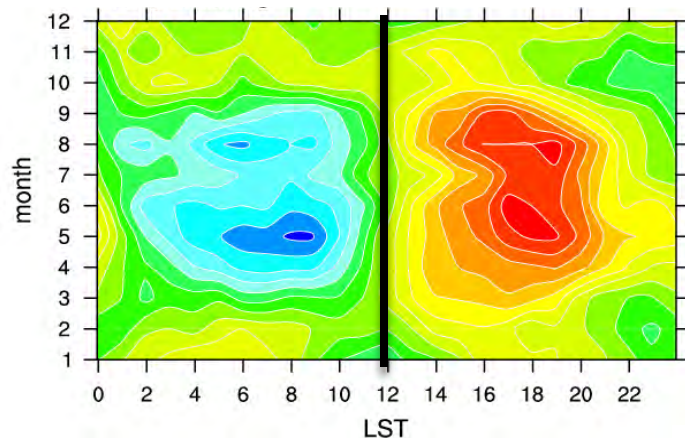
$$ZHD = f(P_s)$$

$$PW = \Pi * ZWD \quad \Pi = f(T_m)$$

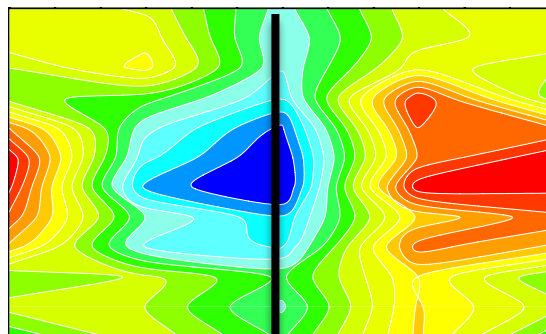


PW Diurnal Variations (Lindenberg)

GPS



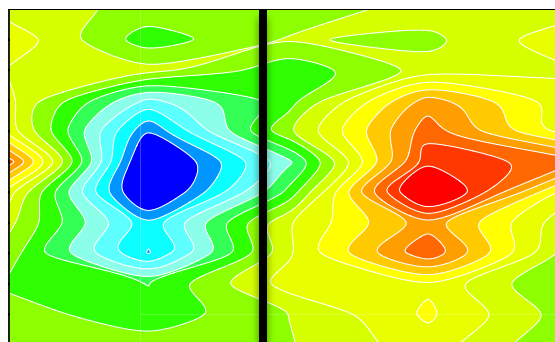
Radiosonde before corr.



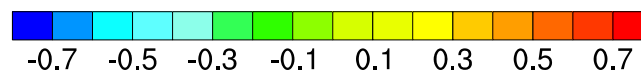
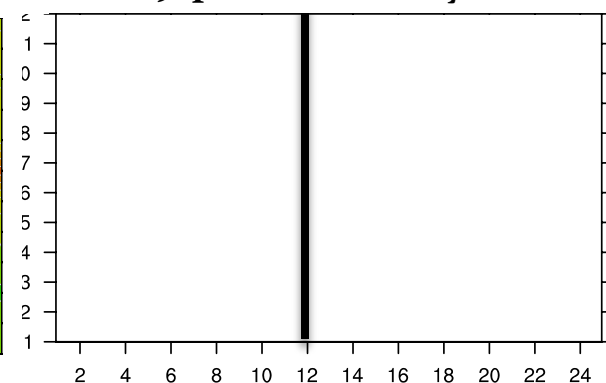
Radiosonde after corr.



ERA-Interim

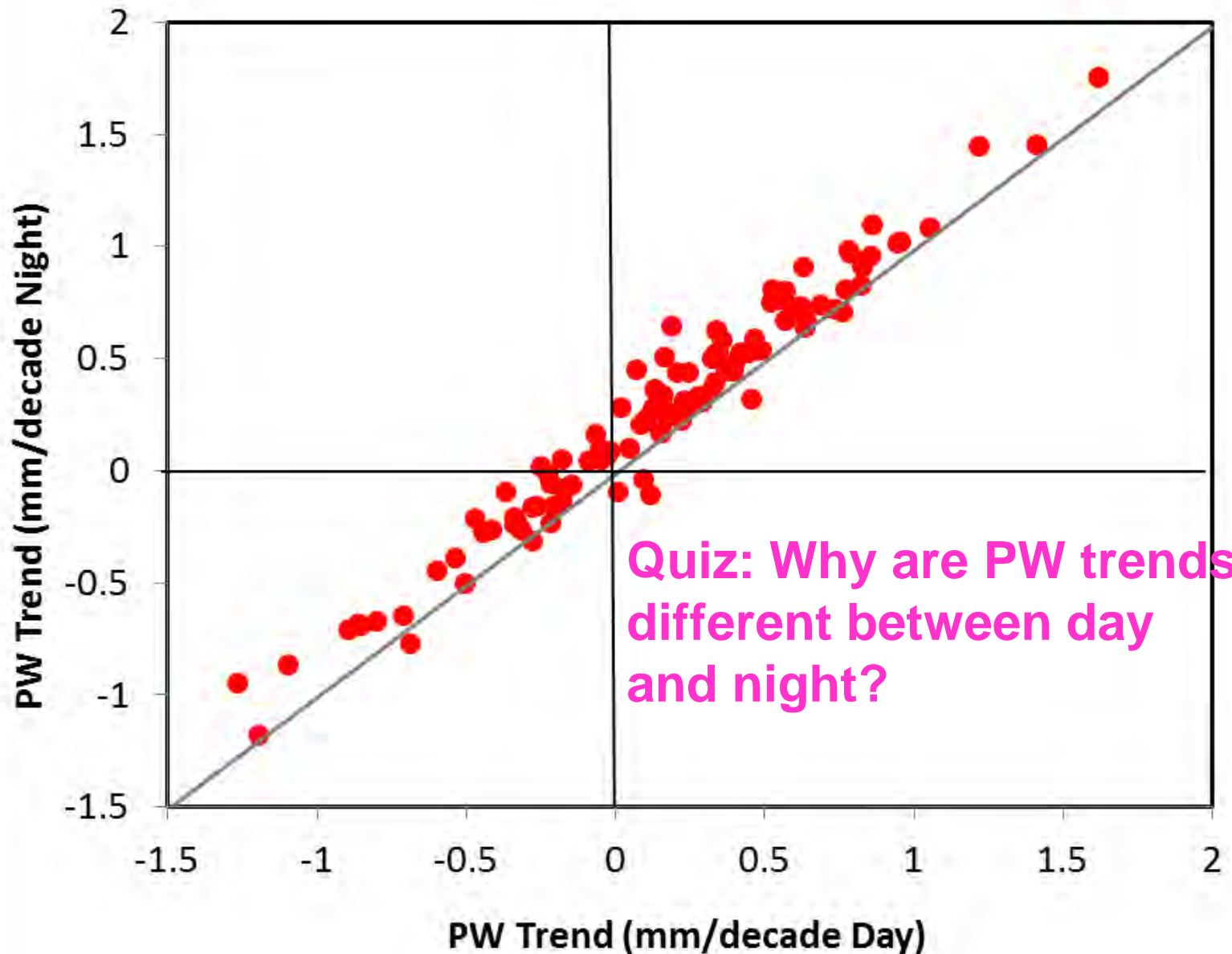


Japanese Reanalysis



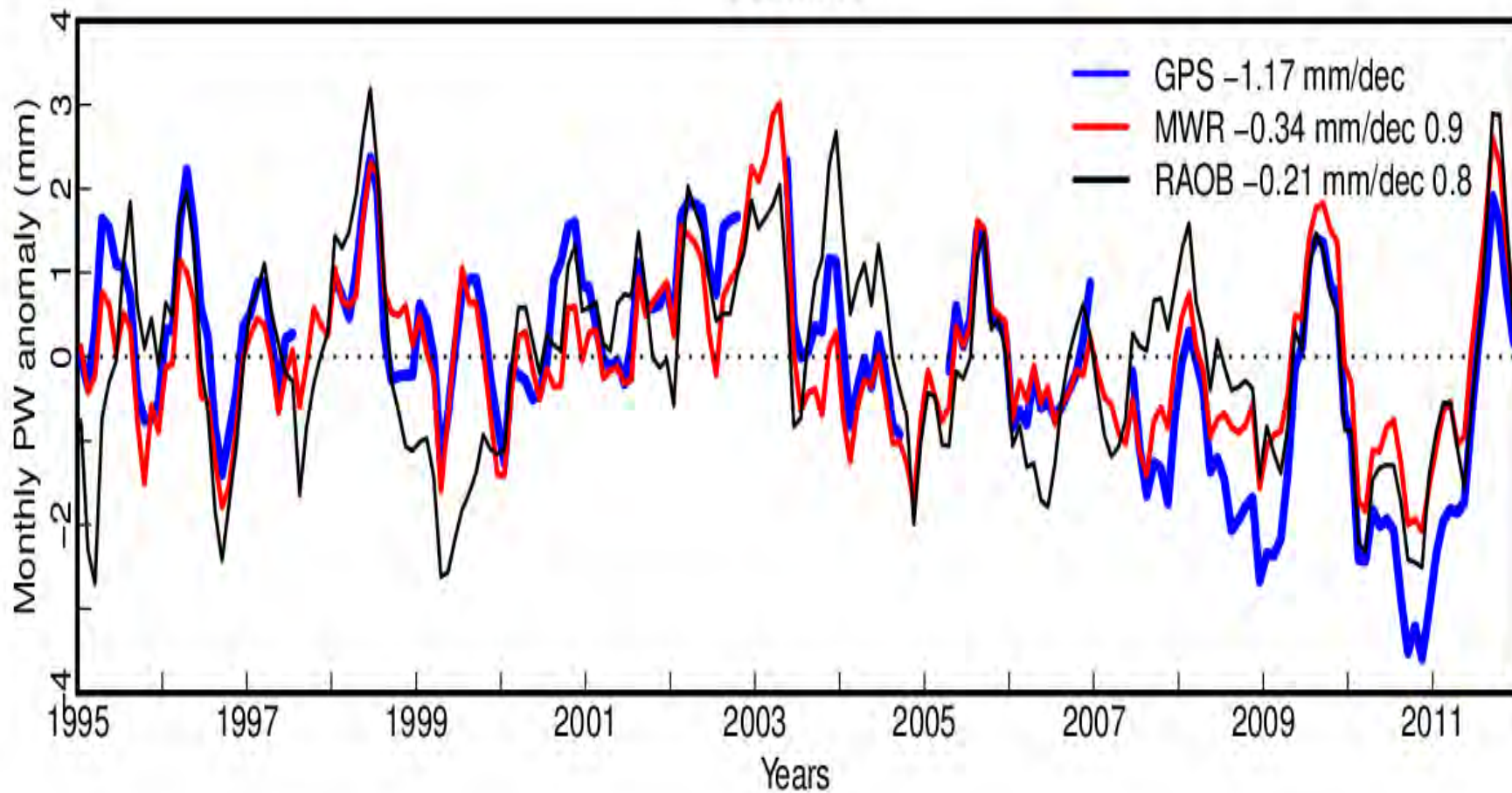
Wang et al. (2013)

Comparisons of Day & Night Trends (GPS)



Redundant Observations

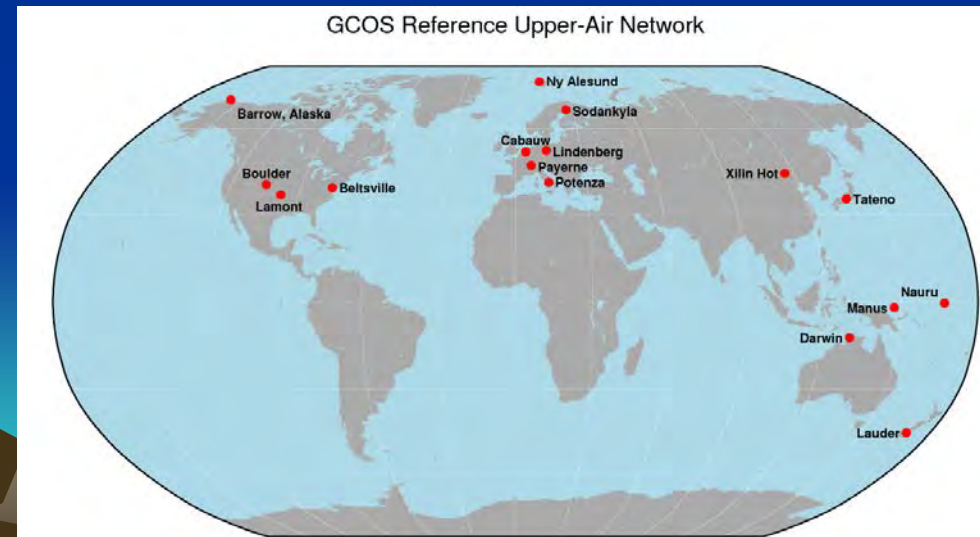
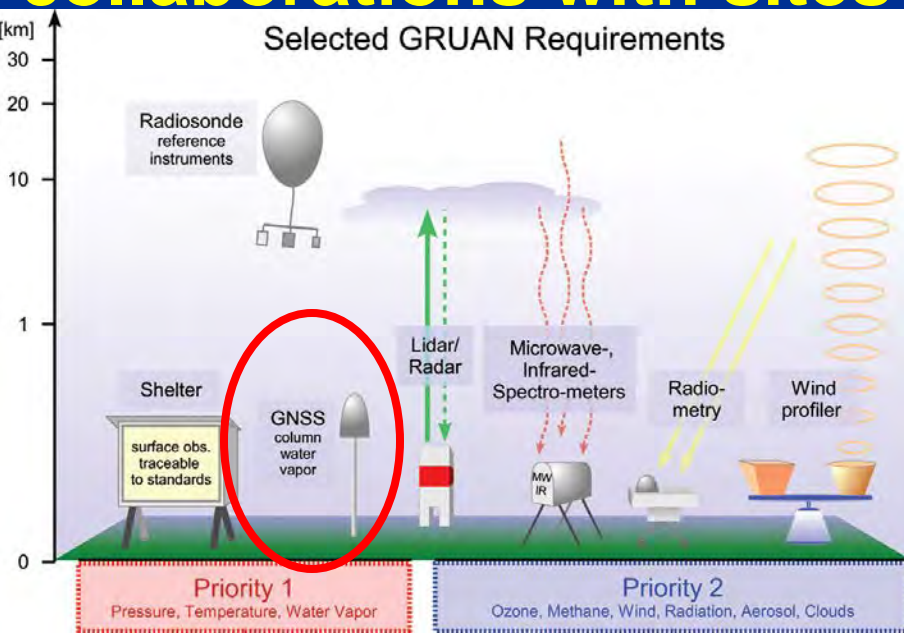
Bermuda



GNSS-PW Task Team: Motivation, Goal, & Operation

Goal: To develop explicit guidance on hardware, software and data management practices to obtain GNSS PW measurements of consistent quality at all GRUAN sites **with eight specific Tasks.**

Operation: Bi-annual conference call, emails, ICMs, sub-teams for each task & documentation, collaborations with sites and GNSS community.



Task	Milestone	Progress
#1 To define GRUAN requirements	“GRUAN GNSS Product Requirements”	Done
#2 To document and review current status	“GRUAN GNSS Site Survey Table”	Done
#3 To prepare “GRUAN GNSS Site Guidelines”	GRUAN TD-6: “GRUAN Ground-based GNSS Site Guidelines”	Done
#4 To develop guidance on data	“GRUAN GNSS Data and Product Table” & “Format Specification for COST-716 Processed GPS Data”	Done
#5 To identify best practices in making and verifying GNSS observations	“Guidelines on use and data exchange protocols for GNSS water vapour in NWP and climate models”	Done
#6 To provide guidelines for GNSS-PW uncertainty analysis	A journal paper	In progress
#7 To recommend practices on managing changes	“Managing changes in GRUAN GNSS-PW product”	Done
#8 To encourage and recommend experiments and research for resolving the tasks		On going

Measurement
the assignment of numbers to
objects or events

level of
measurement
(magnitude)

Dimensions
(units)

Uncertainty
(Error)

No measurement, however carefully made,
can be completely free of uncertainties!!!

$$(\text{measured value of } x) = x_{\text{best}} \pm \delta x.$$

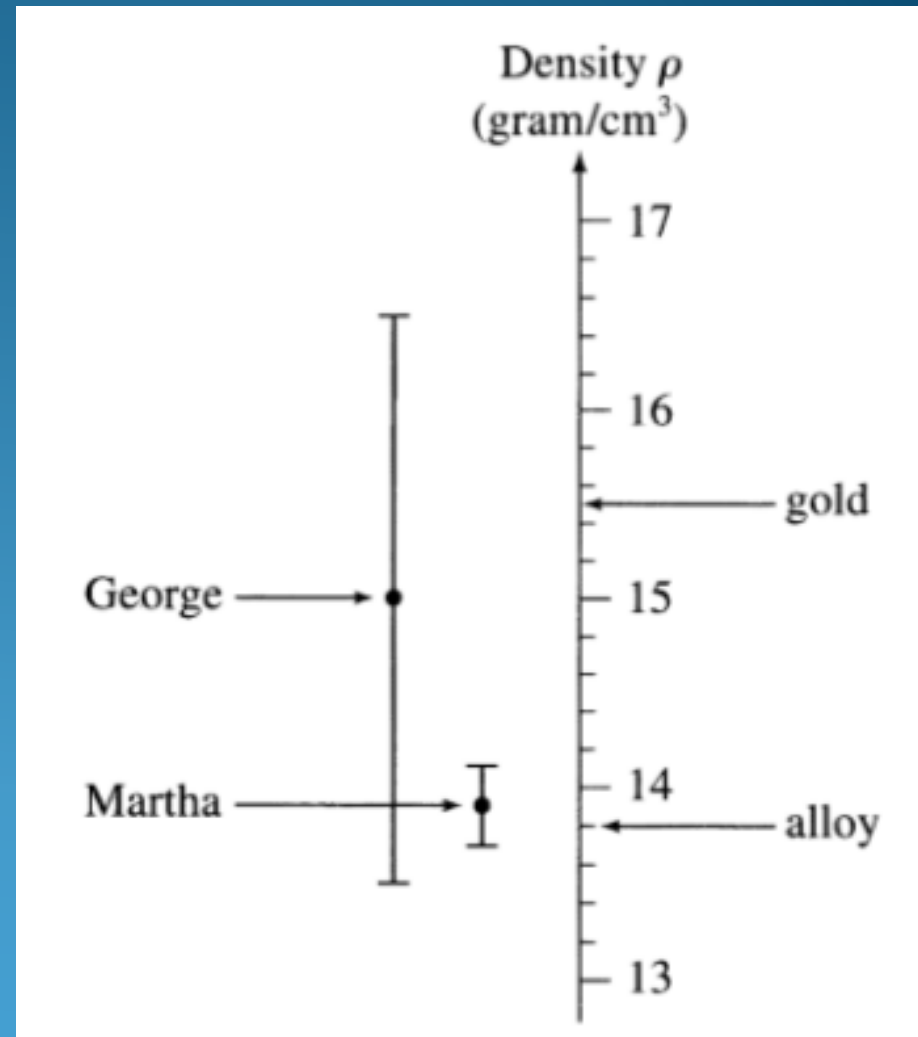
Importance of Knowing the uncertainties

➤ Is a crown made of 18-karat gold or a cheaper alloy?

➤ Fact:

$$\rho_{\text{gold}} = 15.5 \text{ gram/cm}^3$$

$$\rho_{\text{alloy}} = 13.8 \text{ gram/cm}^3.$$



PW Uncertainty Estimation

General Formula for Error Propagation: If $q = q(x, \dots, z)$ is any function of x, \dots, z , then

$$\delta q = \sqrt{\left(\frac{\partial q}{\partial x} \delta x\right)^2 + \dots + \left(\frac{\partial q}{\partial z} \delta z\right)^2}$$

(provided all errors are independent and random)

$$V(\text{PW}) = \frac{ZTD - ZHD}{Q}$$

$$\sigma_V = \sqrt{\left(\frac{\sigma_{ZTD}}{Q}\right)^2 + \left(\frac{\sigma_{ZHD}}{Q}\right)^2 + \left(V \frac{\sigma_Q}{Q}\right)^2}$$

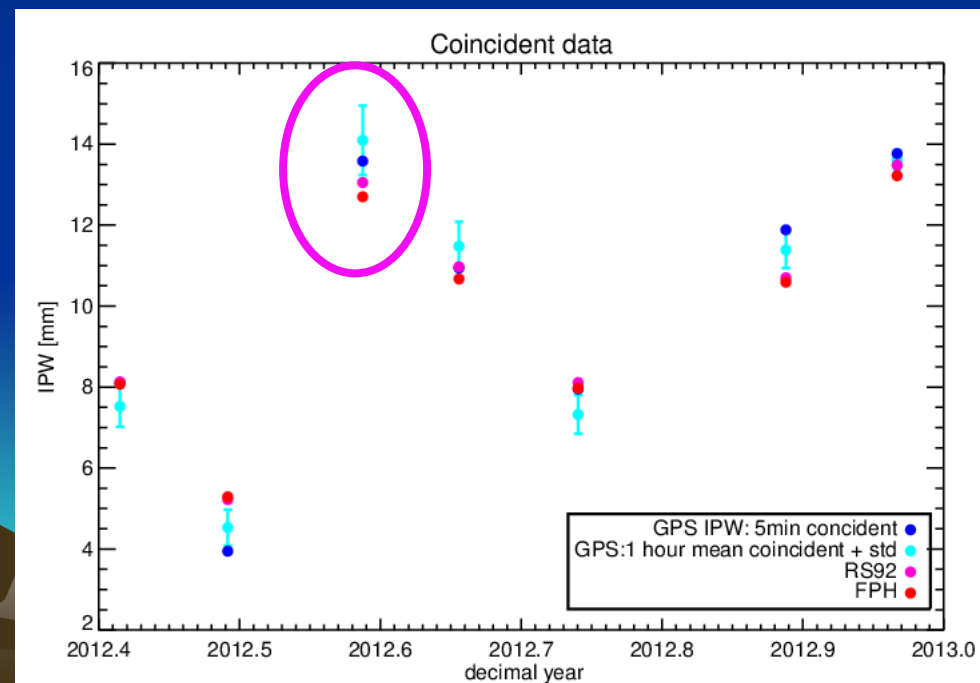
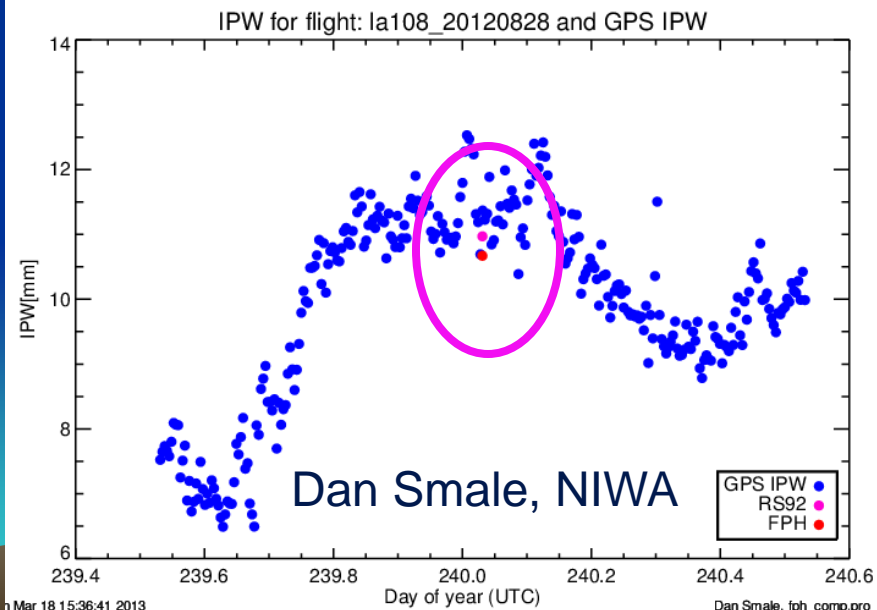
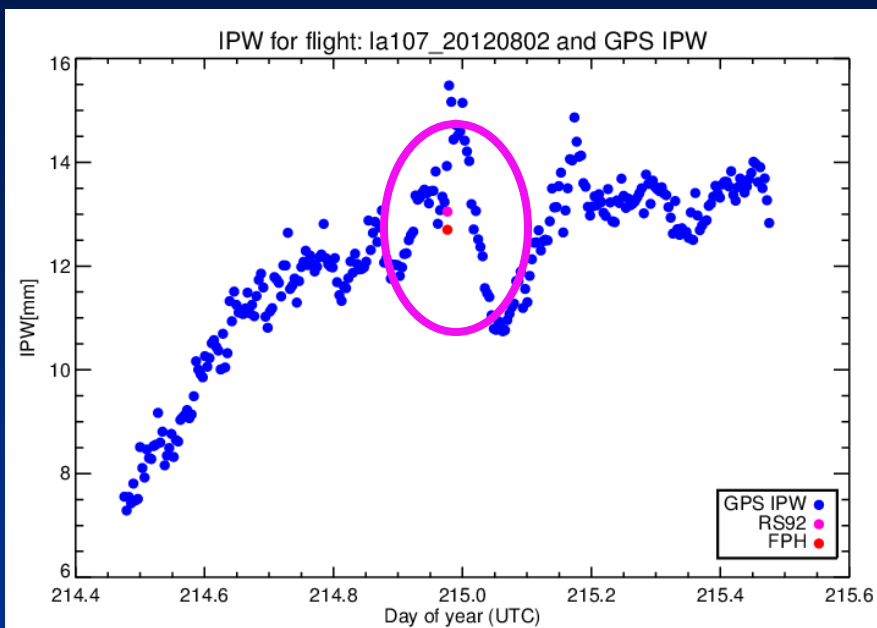
$$\sigma_{IWV} = \sqrt{\left(\frac{\sigma_{ZTD}}{Q}\right)^2 + \left(\frac{2.2768 \sigma_{P_0}}{f(\lambda, H) Q}\right)^2 + \left(\frac{V}{Q} 10^{-6} \rho_w R_w \sqrt{\left(\frac{\sigma_{k_3}}{T_m}\right)^2 + \sigma_{k'_2}^2 + \left(k_3 \frac{\sigma_{T_m}}{T_m^2}\right)^2}\right)^2}$$

PW uncertainty estimation

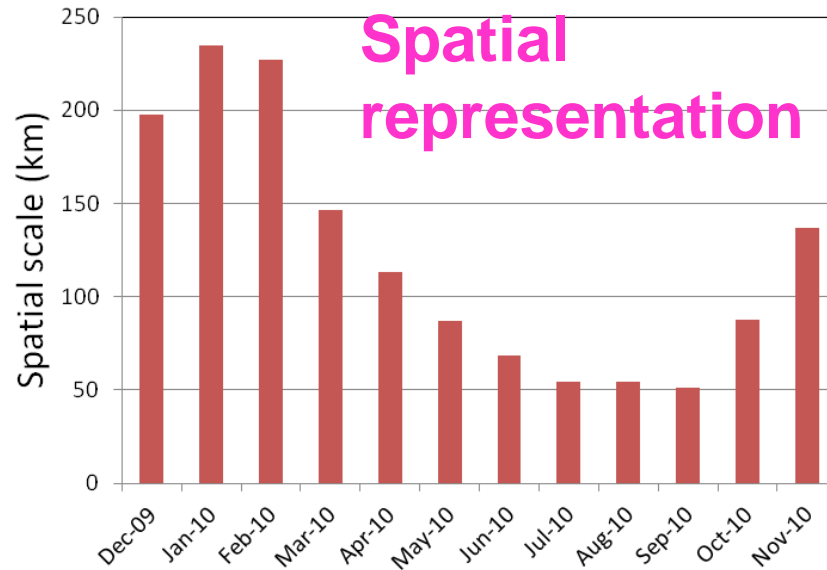
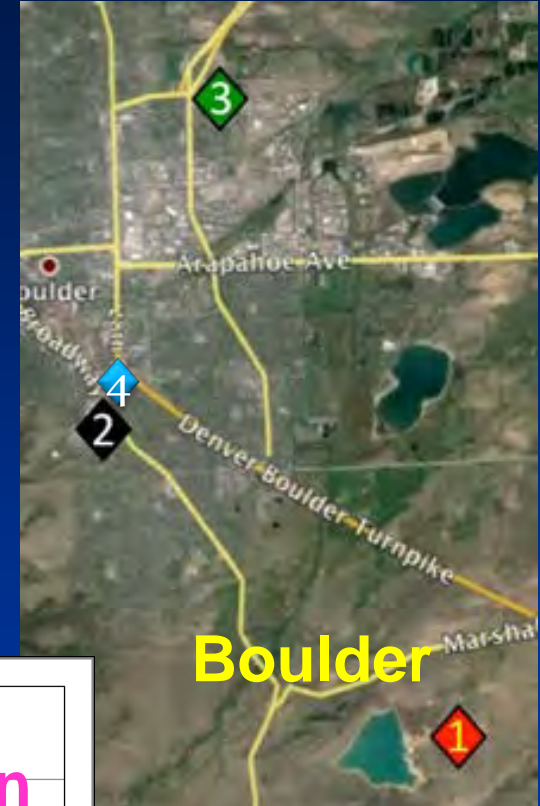
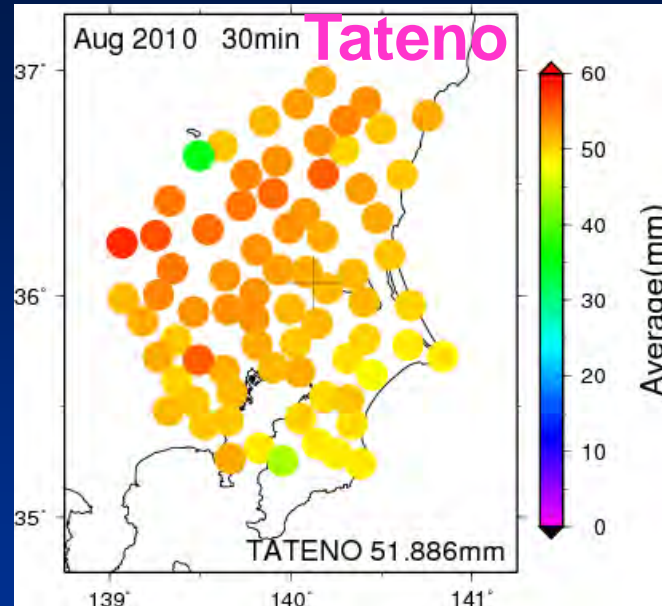
$$\sigma_{IWV} = \sqrt{\left(\frac{\sigma_{ZTD}}{Q}\right)^2 + \left(\frac{2.2768 \sigma_{P_0}}{f(\lambda, H) Q}\right)^2 + \left(\frac{V}{Q} 10^{-6} \rho_w R_w \sqrt{\left(\frac{\sigma_{k_3}}{T_m}\right)^2 + \sigma_{k'_2}^2 + \left(k_3 \frac{\sigma_{T_m}}{T_m^2}\right)^2}\right)^2}$$

1. **ZTD and P0 uncertainties dominate (>94%).**
2. P0 uncertainty: Help from surface obs. group??
3. **Tm uncertainty: calculated from the input source.**
4. ZTD uncertainty: formal error from the ZTD product?
5. **Manuscript on this.**
6. Collaborations with “COST ES1206 - Advanced GNSS Tropospheric Products for monitoring Severe Weather Events and Climate”



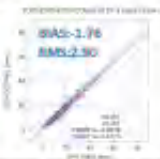
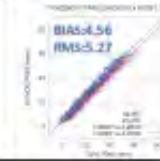
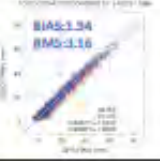
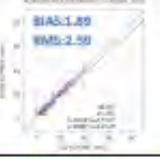
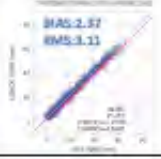
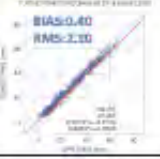
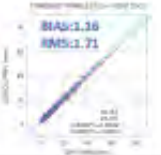
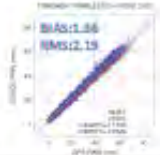
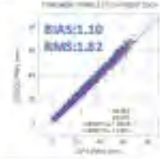
From Guidelines to Implementation: Lauder site



Closely co-located GNSS receivers at GRUAN sites



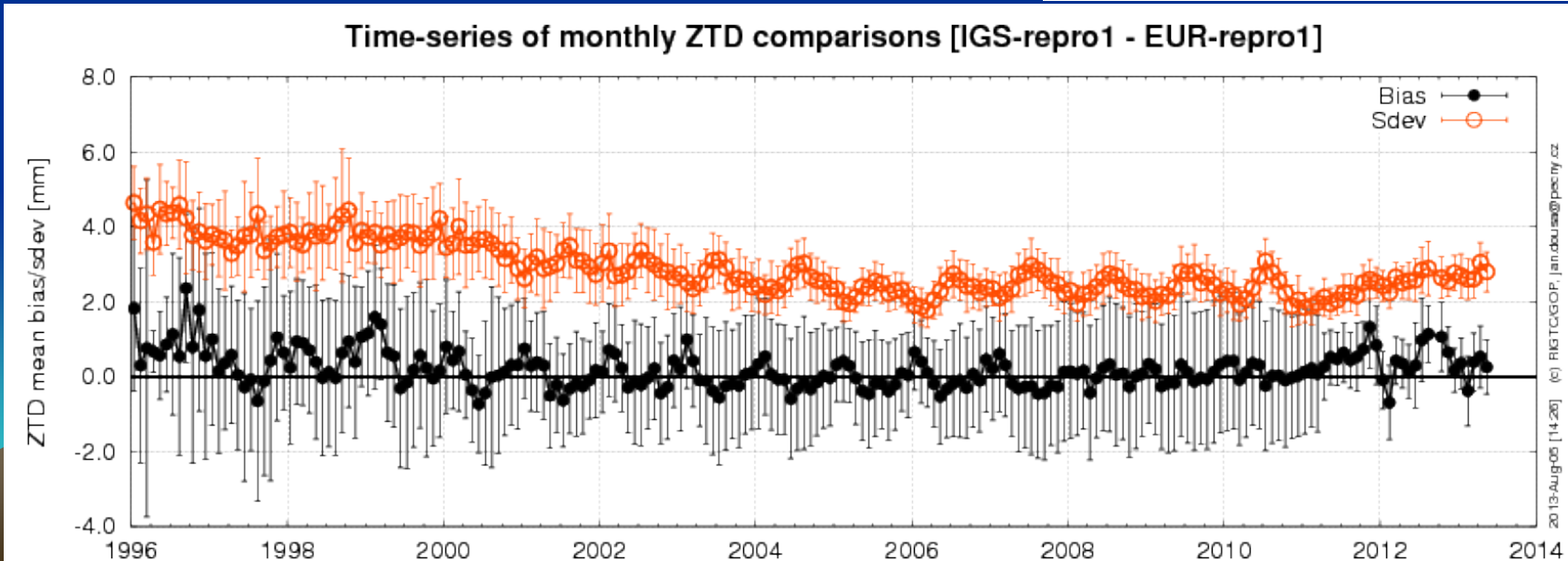
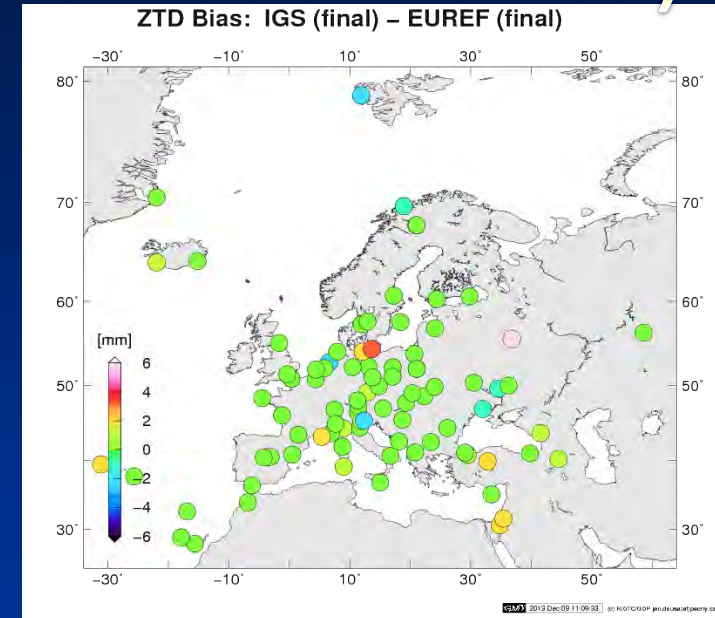
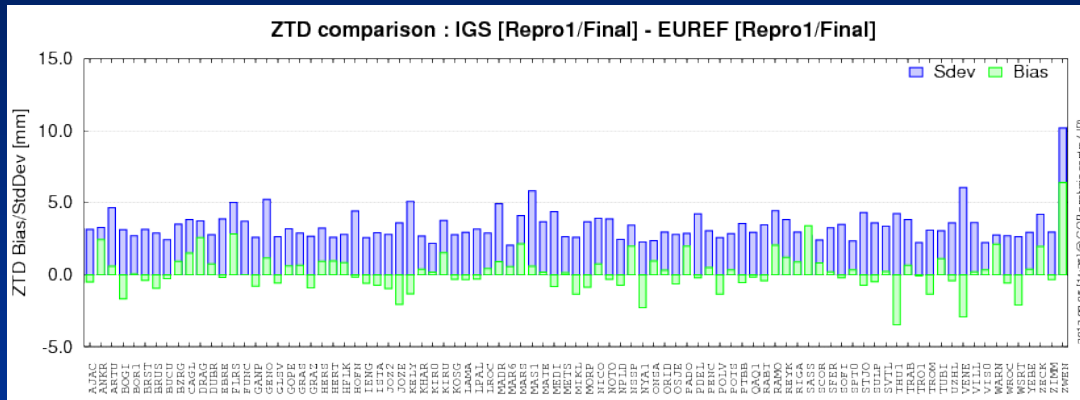
Redundant Observations & Long-term stability

Sonde	RS2-91 (Meisei)								
Ant.	AOAD MT		TRM23903			TRM29659		TOP700779A	
Rec.	SNR8100	BENCHMARK ACT	4000SSE	4000SSI	5700	5700	NETRS	GPR1DY	ZXII3
1994									
1996					http://www.e-trimblegps.com/images/57001mgis.jpg		http://www.inlandgps.com/Products/NetRS-trimmed-Web-04.jpg		
2002									
2003									
2009	http://www.giz.wetzell.de/Infozentrum/Geraetelisten/Positionierungssysteme/MW02-021_1.jpg			http://image.ec21.com/image/satriamanunggal/oimg_GC04358985_CA04358987/Trimble_4000_SSI_2MB_GPS_Reciever_Accessories_4000SSI.jpg				http://x2.audan.com/item_data/thumbnail/20140212/yahoo/c/c418691436.jpg	

Careful assessment of GPS PWV with considering its antenna type, receiver type and accuracy of ephemerides is indispensable prior to use them for climate study.

ZTD & PW comparisons from different techniques (IGS & COST ES1206)

Jan Dousa (Geodetic Observatory Pecny)
(<http://pecny.asu.cas.cz/gop/index.php/gnss-mainmenu-200/troposphere-e-gvapii-mainmenu-63/evaluations>)



Future of GNSS-PW TT

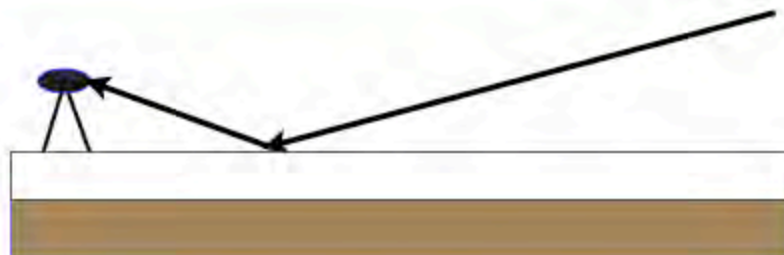
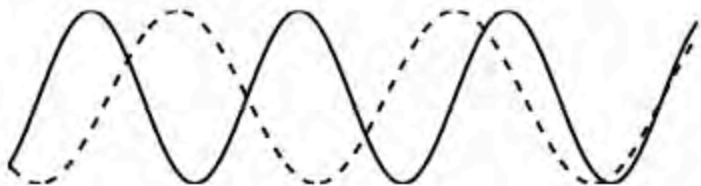
1. Finish un-finished tasks
2. Work with GFZ on updating various guidelines
3. Research: inhomogeneity, reprocessing, ...
4. Expanding GNSS measurements and research beyond PW, such as Slant delay, tomography, reflection signals, GPS-RO, DORIS and so on

Reflected GPS Signals

the reflections off bare soil produce this
SNR curve



add a snow layer



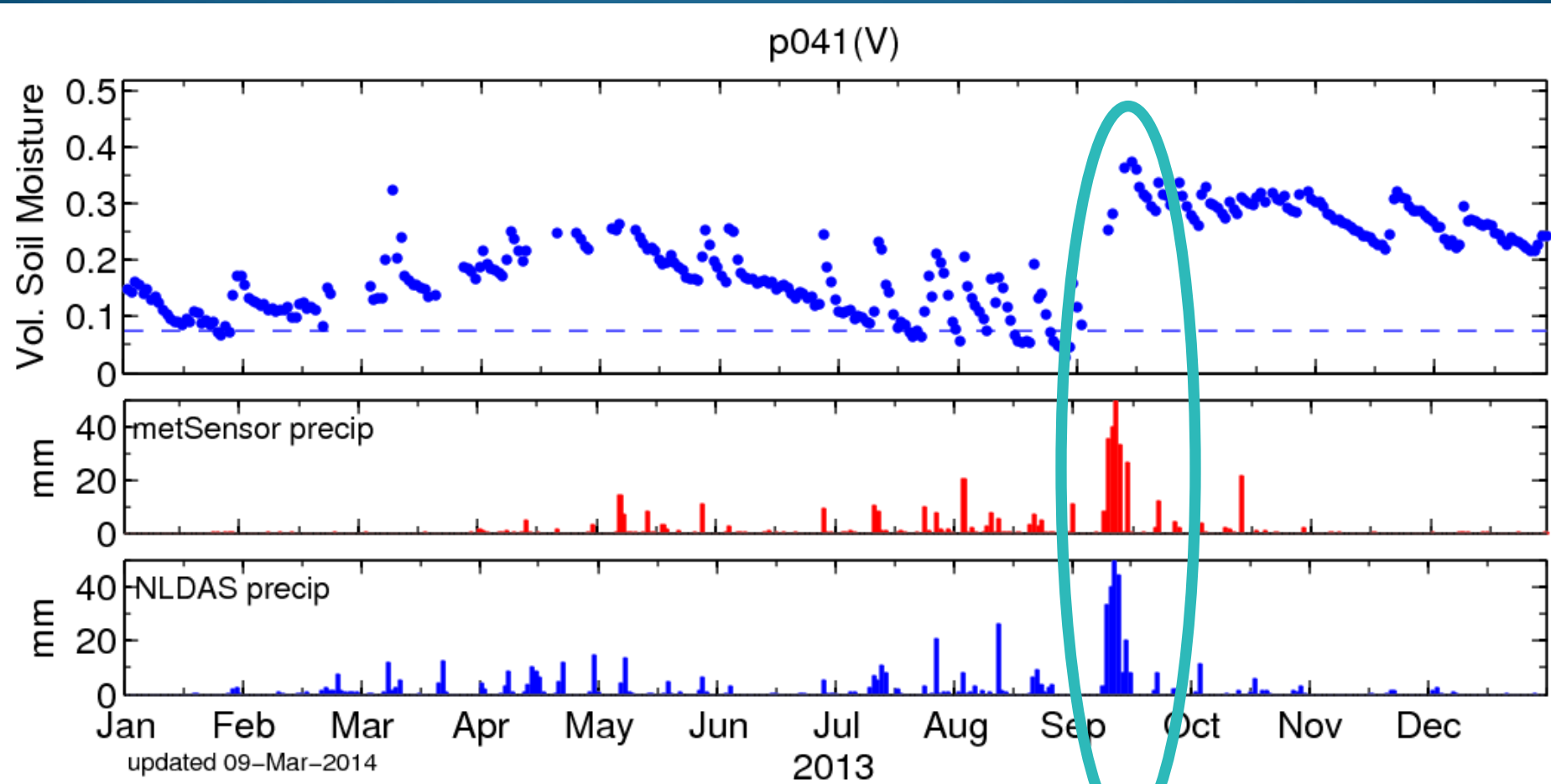
add vegetation



make the soil wet

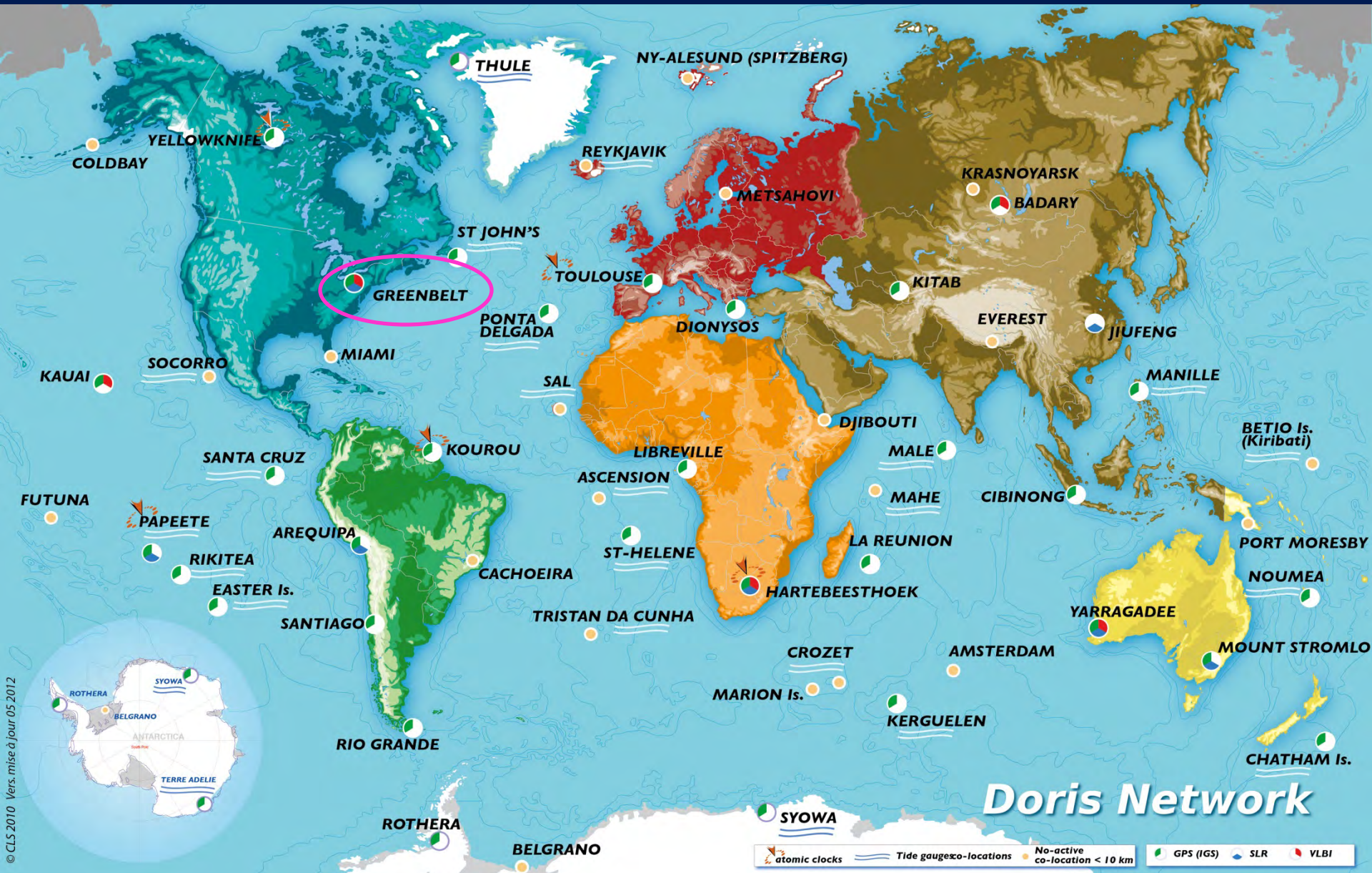


Soil Moisture Data at Marshall, Boulder

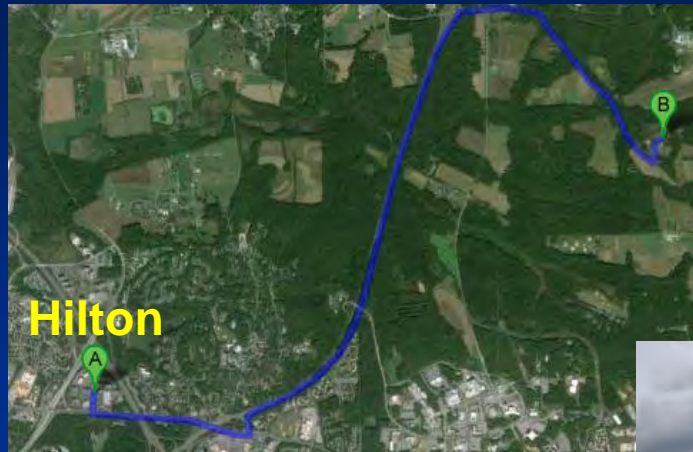


DORIS

(Doppler Orbitography and Radiopositioning Integrated by Satellite)



NASA Goddard Geophysical and Astronomical Observatory



Hilton

