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# Generating Harmonised Fundamental Climate Data Records

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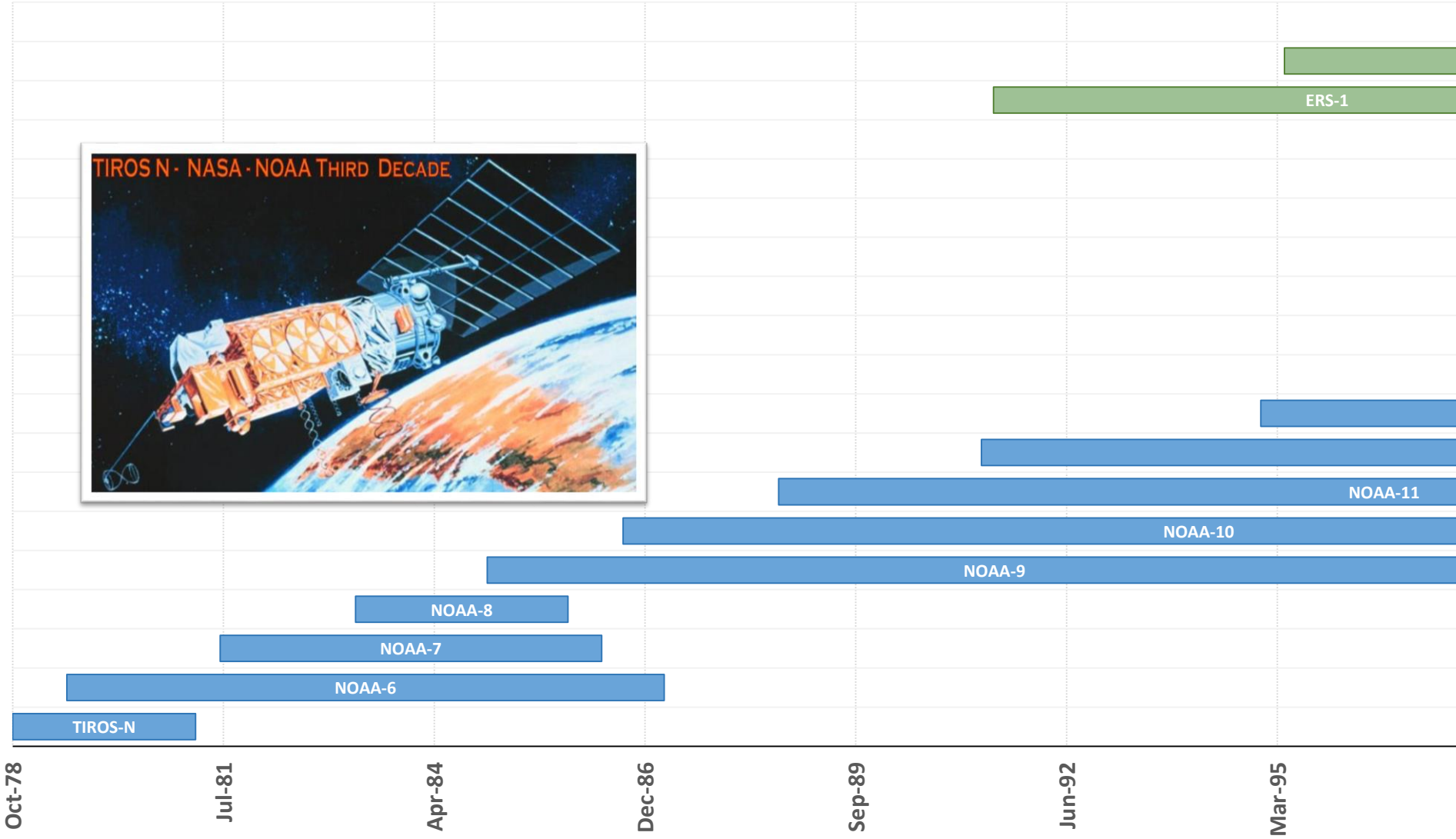
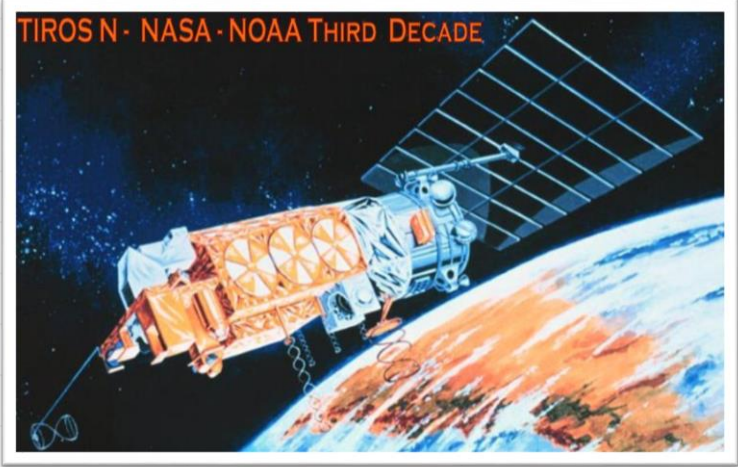
# Contents

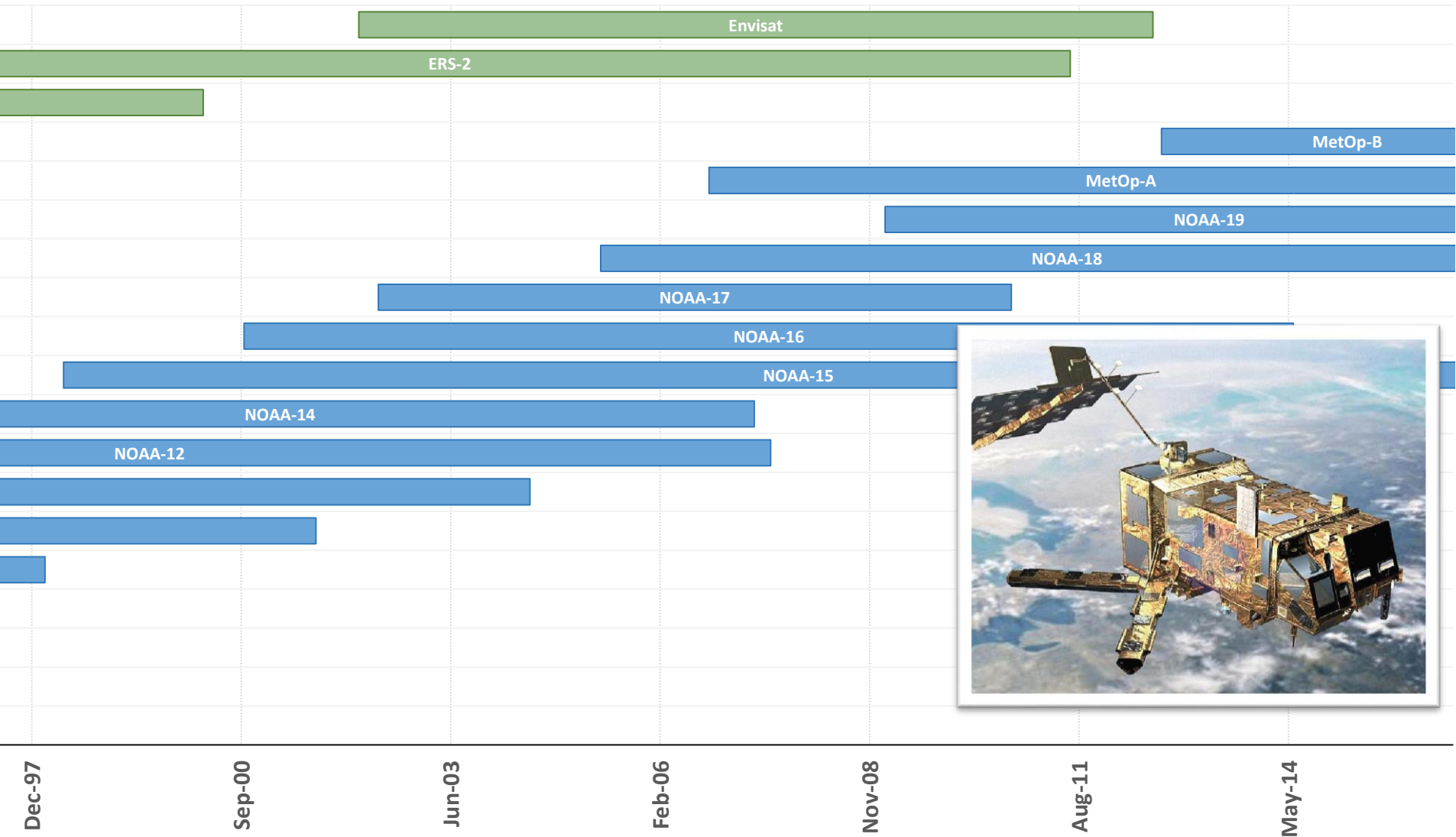
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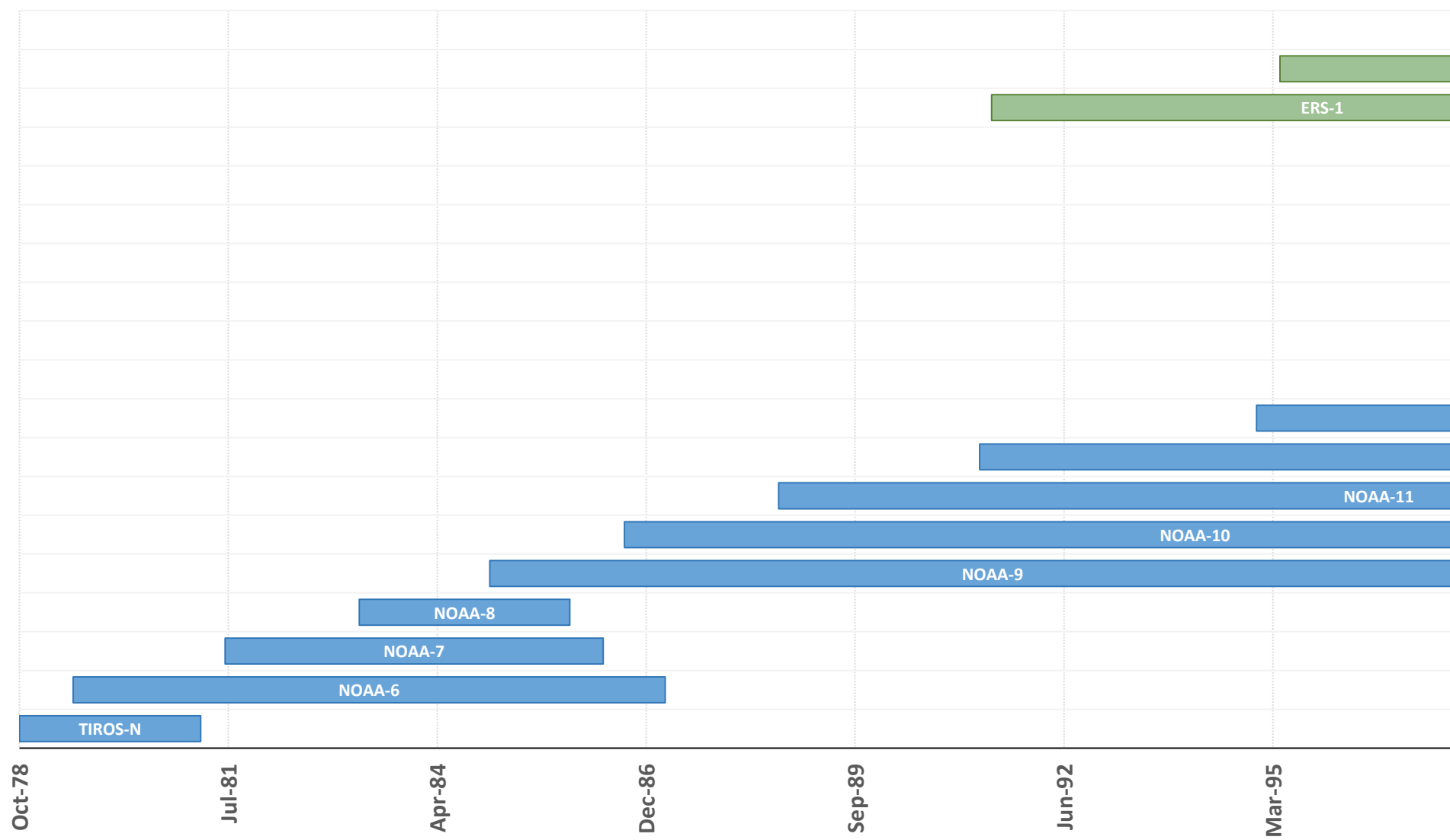
Historical Satellite Records

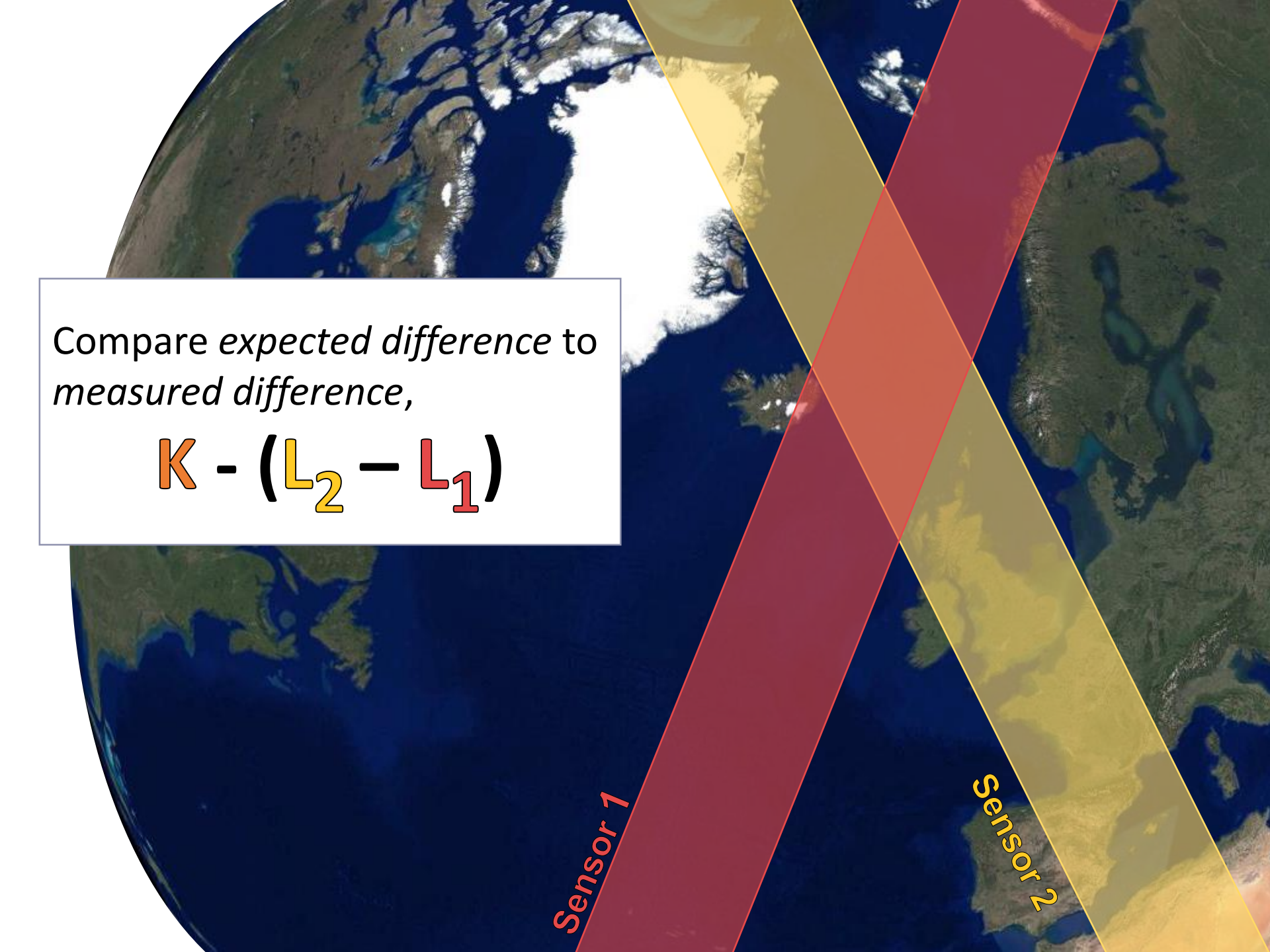
FIDUCEO Project Approach

Harmonisation







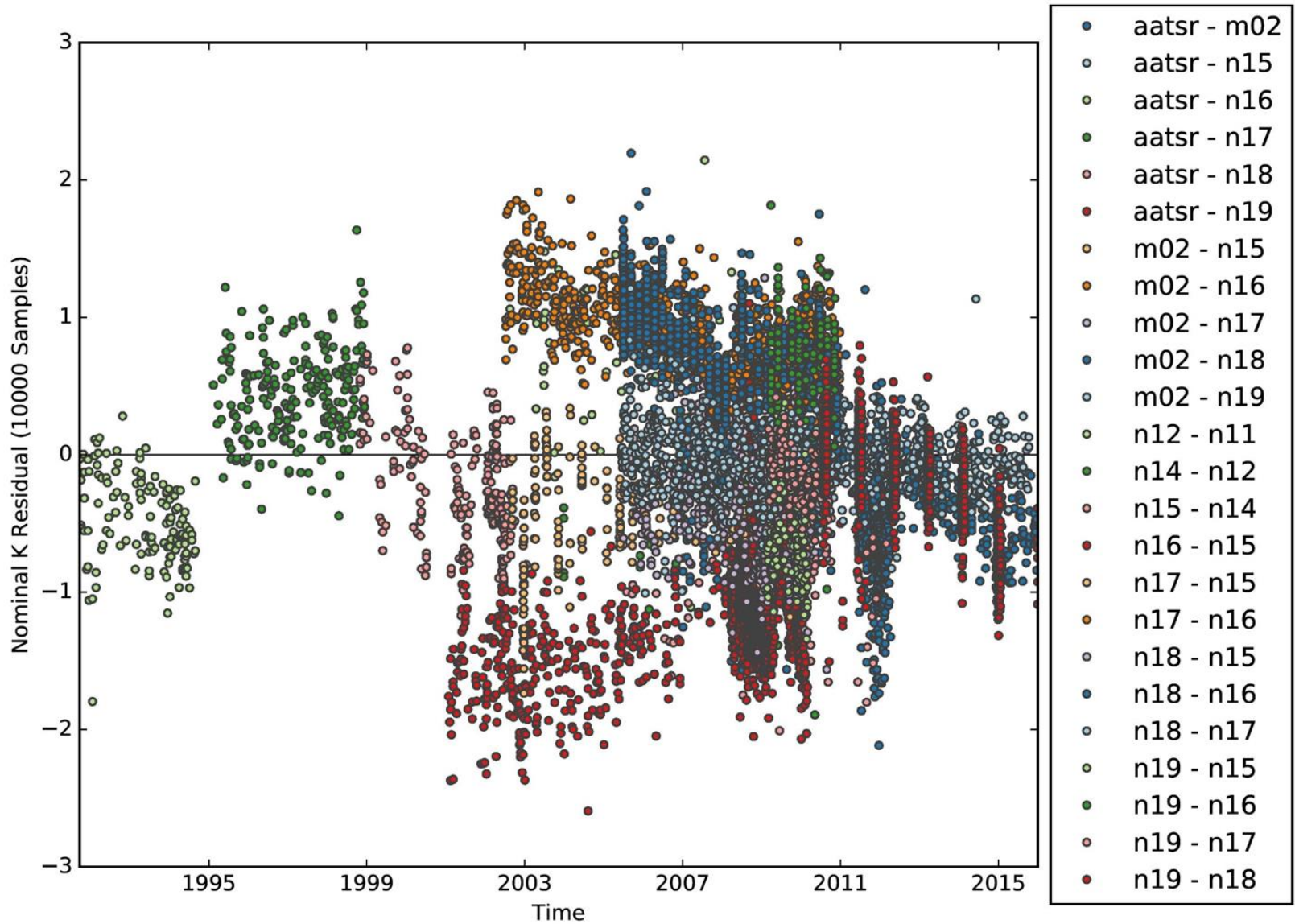
A satellite view of the Earth showing the North Atlantic Ocean and parts of North America and Europe. Two overlapping sensor swaths are shown: a red one labeled 'Sensor 1' and a yellow one labeled 'Sensor 2'. The swaths cross each other over the North Atlantic. A white box with a black border is overlaid on the left side of the image, containing text and a mathematical equation.

Compare *expected difference* to  
*measured difference*,

$$K - (L_2 - L_1)$$

Sensor 1

Sensor 2



# Contents

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Historical Satellite Records

FIDUCEO Project Methodology

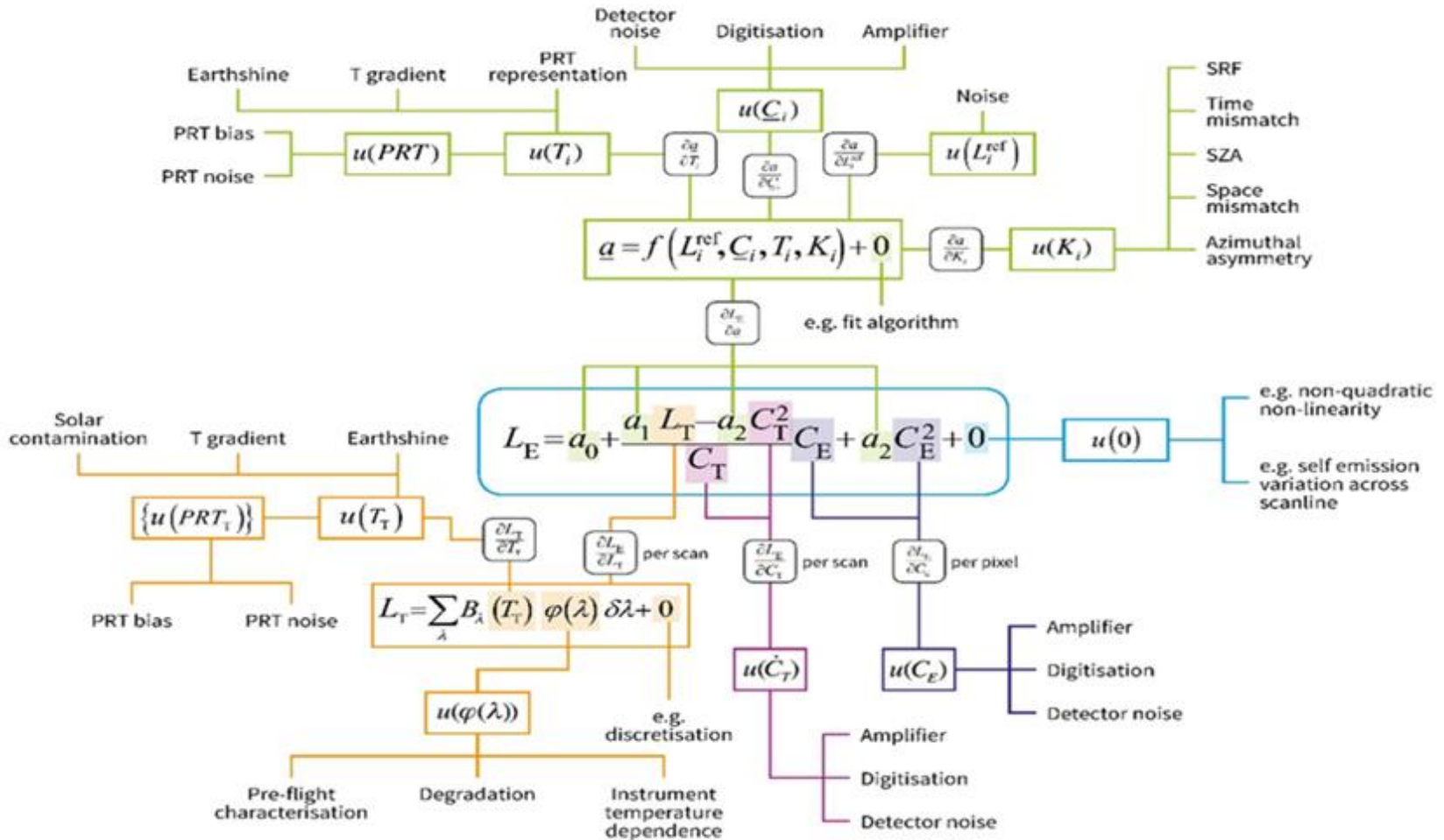
Harmonisation



# Project Sensor Series

DATASET	NATURE	POSSIBLE USES
AVHRR FCDR	Harmonised infra-red radiances and best available reflectance radiances, 1982 - 2016	<b>SST, LSWT, aerosol</b> , LST, phenology, cloud properties, surface reflectance ...
HIRS FCDR	Harmonised infra-red radiances, 1982 - 2016	<b>Atmospheric humidity</b> , NWP re-analysis, stratospheric aerosol ...
MW Sounder FCDR	Harmonised microwave BTs for AMSU-B and equivalent channels, 1992 – 2016	<b>Atmospheric humidity</b> , NWP re-analysis ...
Meteosat VIS FCDR	Improved visible spectral response functions and radiance 1982 to 2016	<b>Albedo, aerosol</b> , NWP re-analysis, cloud, wind motion vectors,...

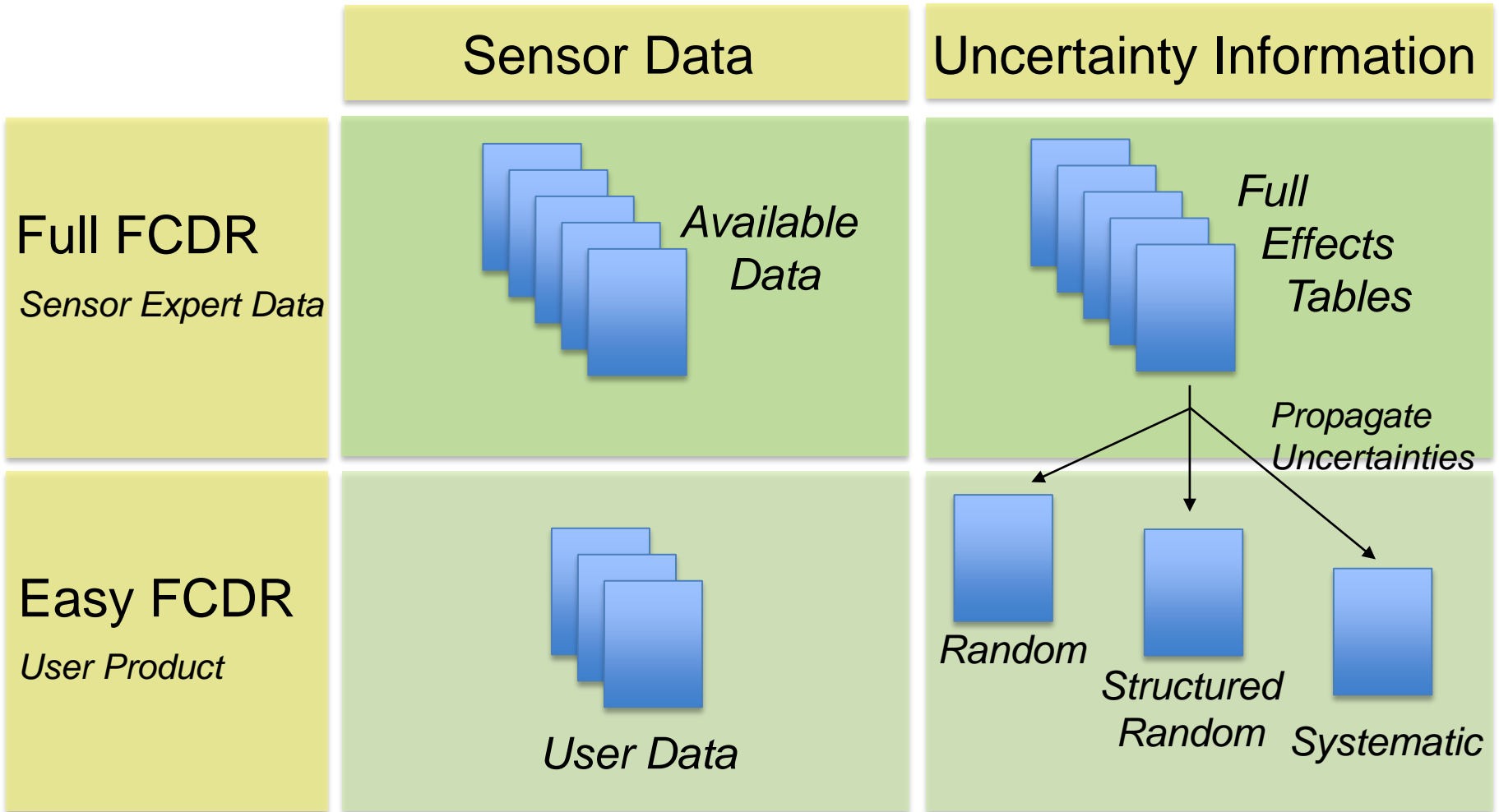
# FIDUCEO Approach – Measurement Tree



# FIDUCEO Approach – Effects Tables

Table descriptor		Value / Expression
Name of effect		
Affected term in measurement function		
Correlation type and form	within scanline [pixels]	
	from scanline to scanline [scanlines]	
	between orbits [orbits]	
	Across time [e.g. days, months, years]	
Correlation scale	within scanline [pixels]	
	from scanline to scanline [scanlines]	
	between orbits [orbits]	
	Across time	
Channels / bands	List channels and bands affected	
	Correlation matrix	
Uncertainty	PDF shape	
	Uncertainty units	
	Uncertainty magnitude	
Sensitivity Coefficient		

# FIDUCEO Approach – File Format



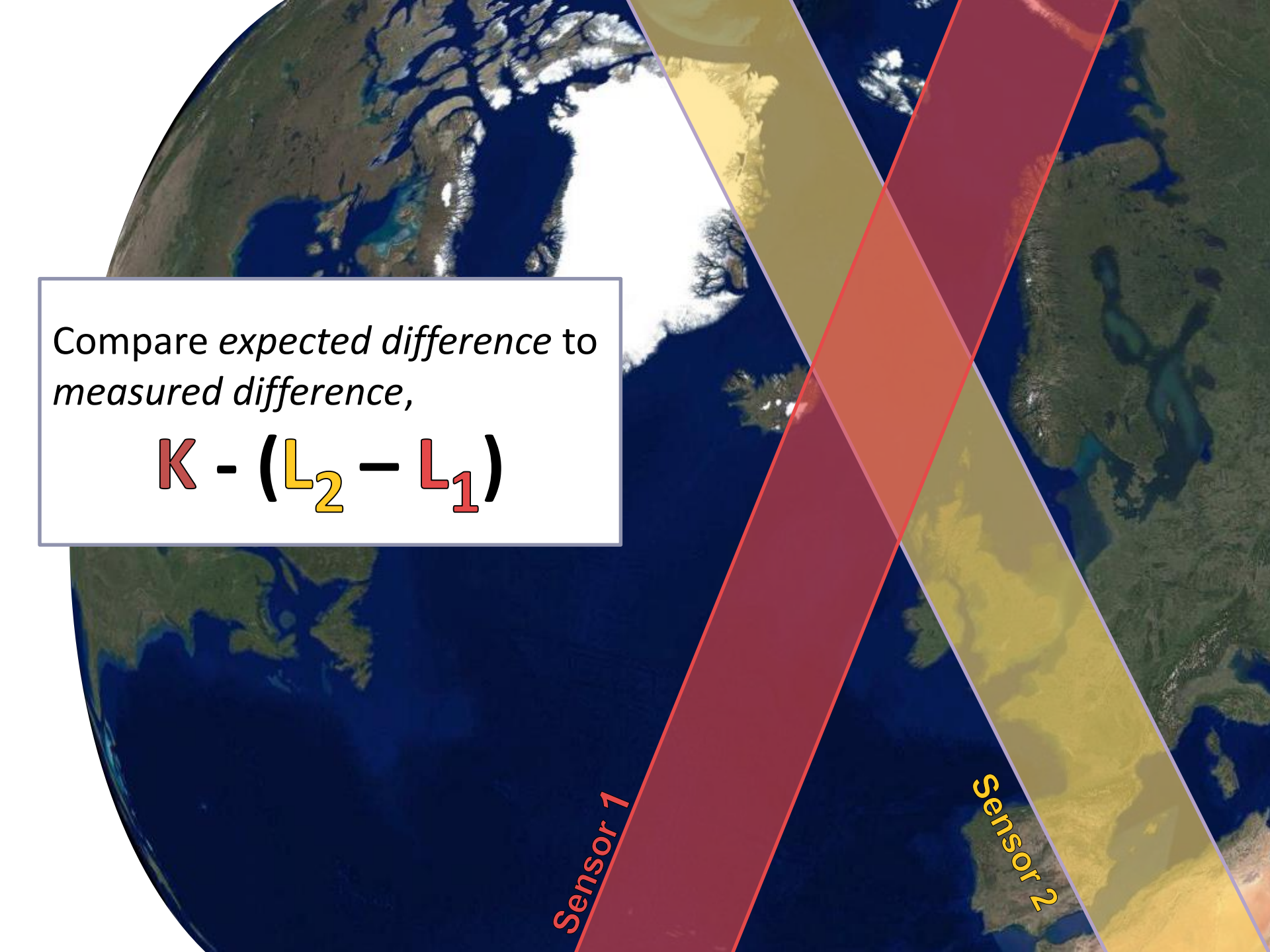
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A satellite view of the Earth showing two overlapping sensor swaths. The swaths are represented by semi-transparent colored bands: a red band labeled 'Sensor 1' and a yellow band labeled 'Sensor 2'. The swaths cross each other in the center of the image. The background shows a portion of the Earth with blue oceans, green landmasses, and white clouds.

Compare *expected difference* to  
*measured difference*,

$$K - (L_2 - L_1)$$

Sensor 1

Sensor 2

# Harmonisation Problem

For match up dataset for full sensor series optimise for,

$$K = L_2 - L_1$$

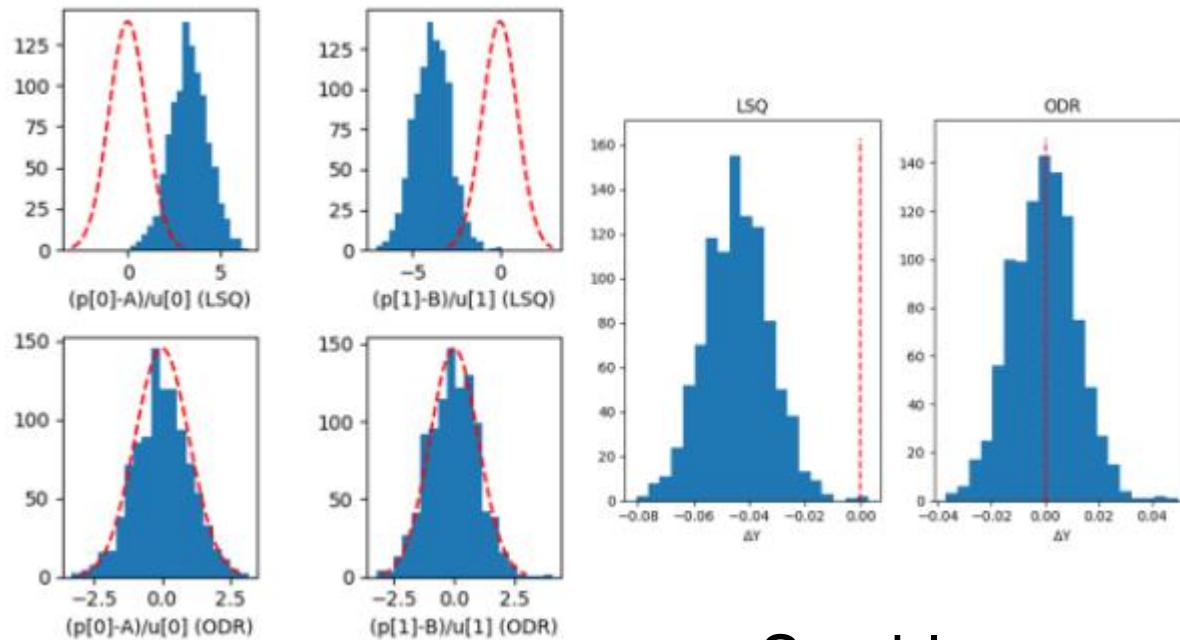
where,

$$L_1 = f_1(X_{1,1} \dots X_{1,N}; \mathbf{a}_1)$$

$$L_2 = \begin{cases} L_{\text{ref}} \\ f_2(X_{2,1} \dots X_{2,N}; \mathbf{a}_2) \end{cases}$$

- Harmonisation Parameters
- Sensor State Variables (i.e. Level 0)

# Least-Squares vs. Errors-in-Variables



See blog:  
[Beyond least squares analysis: Regression considering correlation](#)



# Considering Match-Up Correlation

		Random Error Effects	
		Independent	Structured
Systematic Error Effects	No Common Error	1 – Random Representation: $u_r(\underline{X})$	3 – Structured Random Representation: $\hat{W}, u_r(\tilde{X})$
	Common Error	2 – Random + Systematic Representation: $u_r(\underline{X}), u_s(\underline{X})$	4 – Structured Random + Systematic Representation: $\hat{W}, u_r(\tilde{X}), u_s(\tilde{X})$

# 'Errors-in-variables' problem

Challenging due to:

- Size of data set ( $>10^8$  matches)
- Highly correlated errors

Develop Novel Methods

First transform into data  $X$  to independent variables  $\tilde{X}$ , so have problem

Data

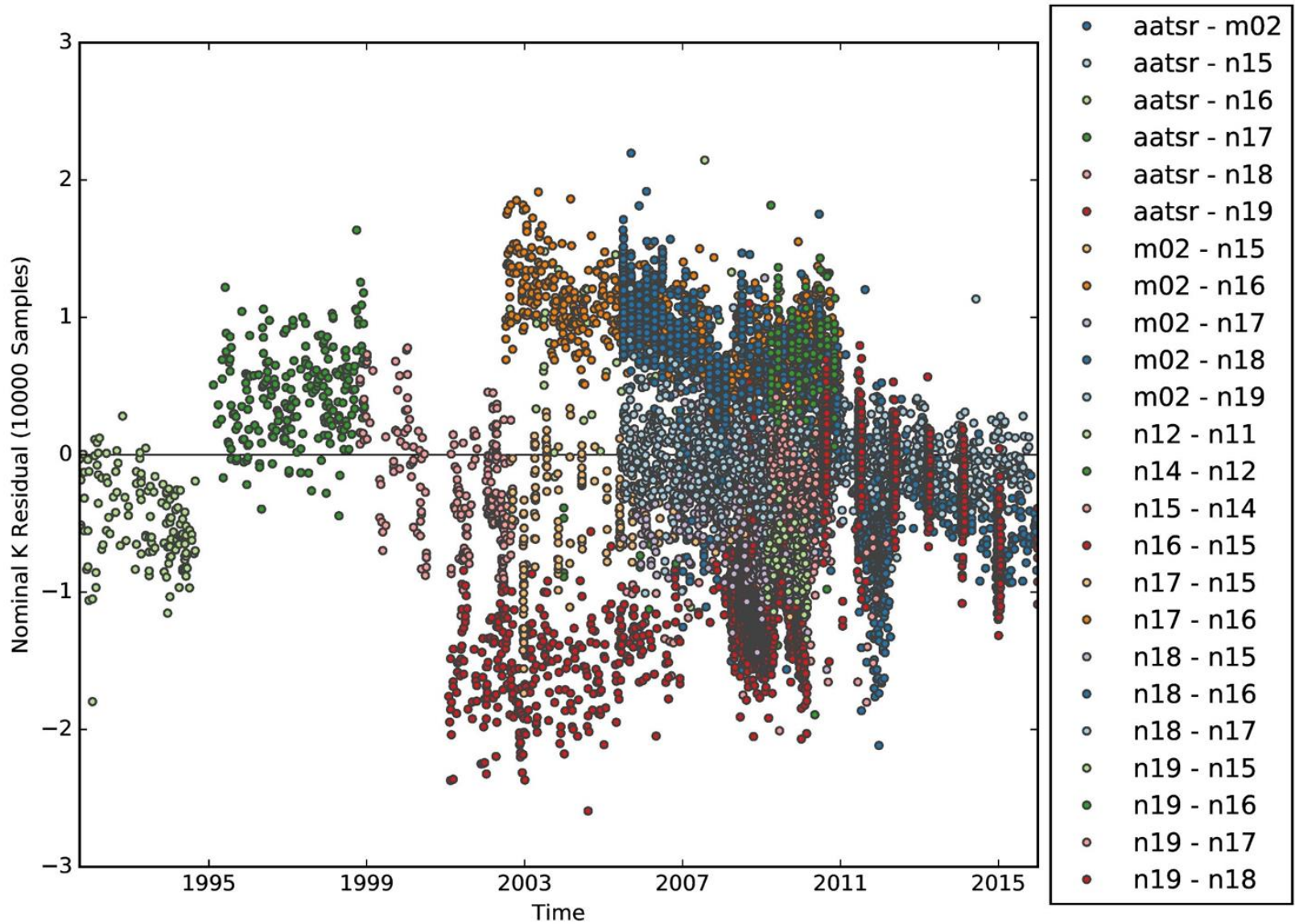
$\tilde{L}_{\text{ref}}^{\text{data}}, \tilde{X}^{\text{data}}, \tilde{K}^{\text{data}}$

Parameters

$\tilde{L}_{\text{ref}}, \tilde{X}, \tilde{K}, a_t, \dots$

Objective function

$$F \equiv (\tilde{L}_{\text{ref}}^{\text{data}} - \tilde{L}_{\text{ref}})^T (\tilde{L}_{\text{ref}}^{\text{data}} - \tilde{L}_{\text{ref}}) + (\tilde{X}^{\text{data}} - \tilde{X})^T (\tilde{X}^{\text{data}} - \tilde{X}) + (\tilde{K}^{\text{data}} - \tilde{K})^T (\tilde{K}^{\text{data}} - \tilde{K})$$

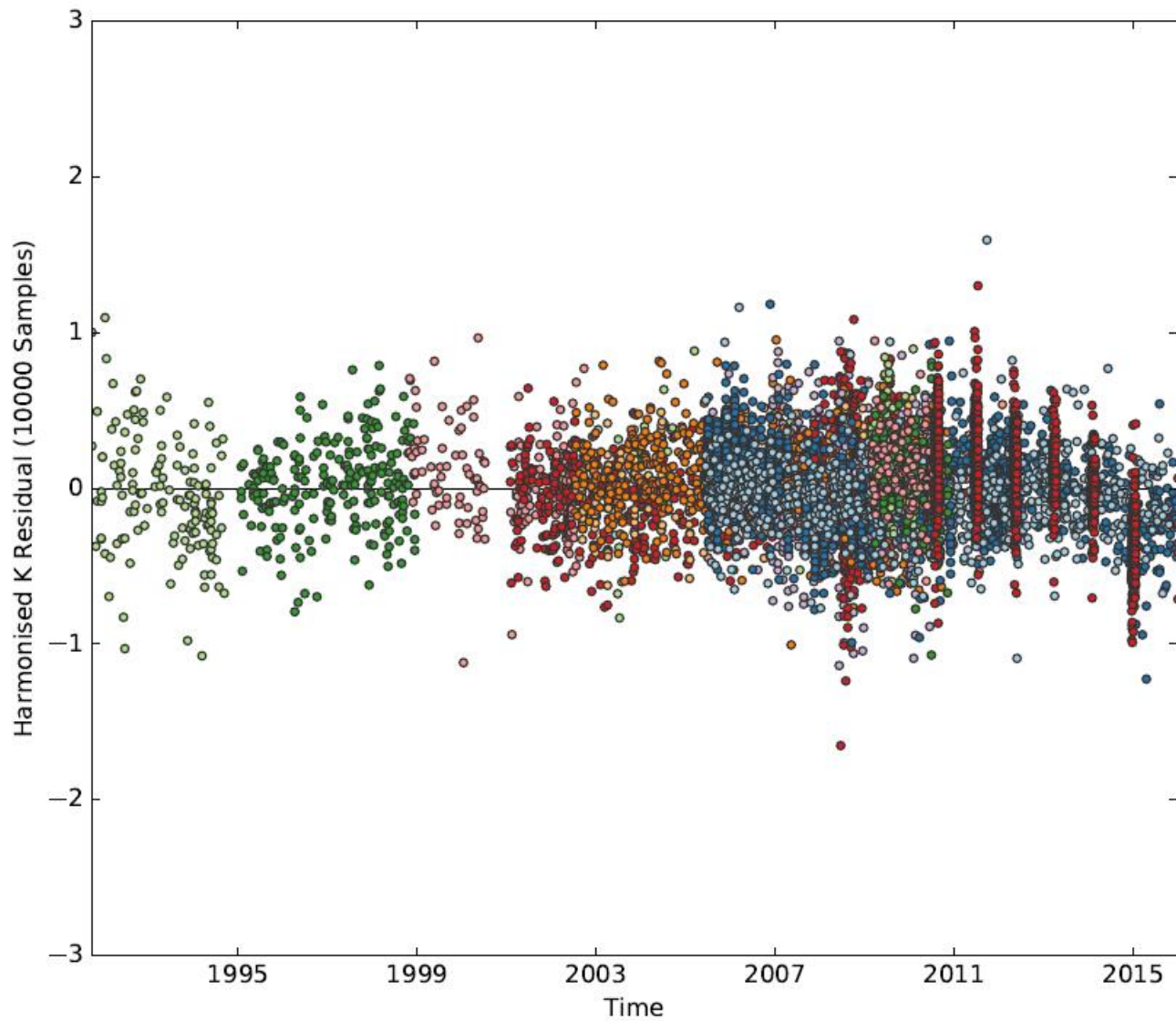


# Example: AVHRR

- Sensor Measurement Function (Simplified),

$$L_E = a_0 + \frac{(\epsilon + a_1)L_{ICT}}{\bar{C}_S - \bar{C}_{ICT}} (\bar{C}_S - C_E) + a_2(\bar{C}_{ICT} - C_E)(\bar{C}_S - C_E)$$

- Harmonisation Parameters
- Sensor State Data
- Sensor Constant



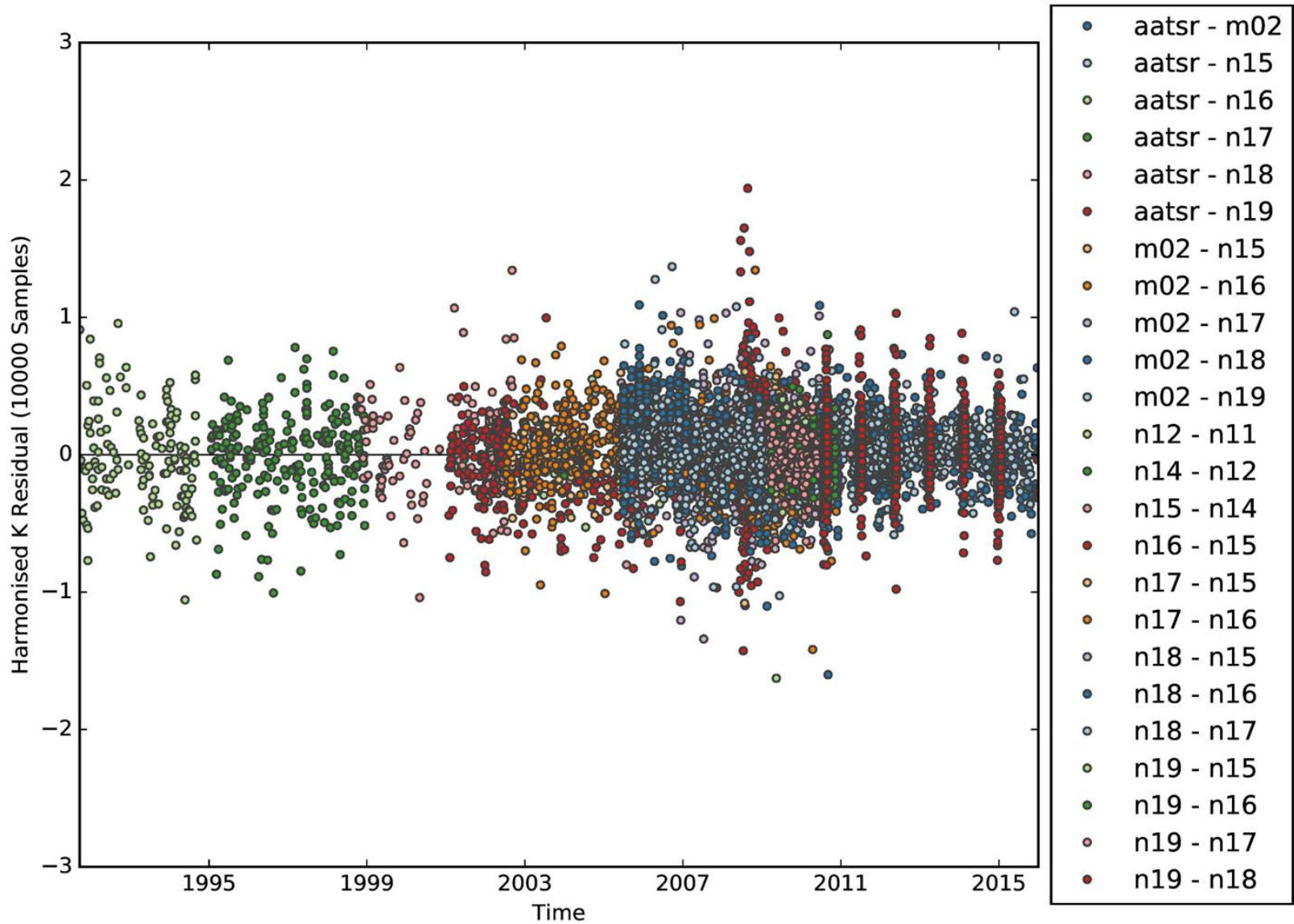
- aatsr - m02
- aatsr - n15
- aatsr - n16
- aatsr - n17
- aatsr - n18
- aatsr - n19
- m02 - n15
- m02 - n16
- m02 - n17
- m02 - n18
- m02 - n19
- n12 - n11
- n14 - n12
- n15 - n14
- n16 - n15
- n17 - n15
- n17 - n16
- n18 - n15
- n18 - n16
- n18 - n17
- n19 - n15
- n19 - n16
- n19 - n17
- n19 - n18

# Example: AVHRR

- Sensor Measurement Function (more complex),

$$L_E = a_0 + \frac{(\epsilon + a_1)L_{ICT}}{\bar{C}_S - \bar{C}_{ICT}} (\bar{C}_S - C_E) + a_2(\bar{C}_{ICT} - C_E)(\bar{C}_S - C_E) + a_3T_O$$

- Harmonisation Parameters
- Sensor State Data
- Sensor Constant



Thank you!

<https://www.fiduceo.eu>