

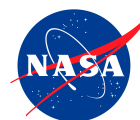


Jason-1 GDR Quality Assessment Report

Cycle 268

10-04-2009 / 20-04-2009

| | | |
|---------------|---|--|
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1. Introduction. Document overview

The purpose of this document is to report the major features of the data quality from the Jason-1 mission. The document is associated with data dissemination on a cycle per cycle basis. This document reports results from Jason-1 GDRs.

The objectives of this document are :

- To provide a data quality assessment
- To provide users with necessary information for data processing
- To report any change likely to impact data quality at any level, from instrument status to software configuration
- To present the major useful results for the current cycle

It is divided into the following topics :

- General quality assessment and cycle overview**
- Poseidon-2 altimeter and sensor**
- CALVAL main results**
- Jason-1 Long term performance monitoring**
- Mean Sea Level (MSL)**
- Particular investigations**

2. General quality assessment and cycle overview

2.1. Software version

This cycle has been produced with the CMA Reference Software V9.2_03. Since CMA version V9.1_02 (corresponding to cycle 220), DORIS TEC data are no longer computed. They are replaced by GIM model ionosphere correction. The results presented in this report have been performed with GDR products in version B for cycles 1 to 232, and in version C since cycle 233 onwards.

2.2. Cycle quality and performances

Data quality for this cycle is nominal.

Analysis of crossovers and sea surface variability indicate that system performances are close to usual values that are obtained from the TOPEX/POSEIDON data. For this cycle, the crossover standard deviation is 6.07 cm rms. When using a selection to remove shallow waters (1000 m), areas of high ocean variability and high latitudes ($> |50|$ deg.) it decreases down to 5.30 cm rms.

The standard deviation of Sea Level Anomalies (SLA) relative to a 7-year mean (based on T/P data) is 10.95 cm. When using a selection to remove shallow waters (1000 m), areas of high ocean variability and high latitudes ($> |50|$ deg) it lowers to 10.14 cm .

- Performances from crossover differences are detailed in the dedicated [section Crossover statistics](#).
- Detailed CALVAL results are presented in [section 3](#).
- Note that since cycle 262, Jason-1 is on its new interleaved ground-track.
- A Yaw Flip was performed on 2009-04-13 from 02 :02 :27 to 02 :21 :28 (pass 61).
- A Yaw Ramp(Fixed to Sinusoid BETAP=+15.0) was performed on 2009-04-18 from 03 :40 :28 to 03 :42 :35 (pass 190).

2.3. Missing measurements

This cycle has no missing pass. Missing measurements relative to a nominal ground track are plotted on [section Missing measurements](#).

2.4. End of scientific mission for TOPEX/Poseidon

Since cycle 139, there are no results from intercalibration between Jason-1 and TOPEX/Poseidon data. During TOPEX/Poseidon cycle 481, on 9th October 2005, the pitch reaction wheel showed an anomalous behavior, followed by stalling. Despite of several attempts to restart the wheel, it continues to stop working after a short warm-up phase. In consequence the TOPEX/Poseidon satellite is currently in a sun-pointing safe mode on two-wheel control.

2.5. Impact of product version "c"

2.5.1. Editing procedure

For GDR version "c" the same editing criteria and thresholds like in GDR version "b" should be used. Since GDR version "b" the MLE4 retracking algorithm is used. It is based on a second-order altimeter echo model and is more robust for large off-nadir angles (up to 0.8 degrees). For product version "a" (CMA version 6.3), the maximum threshold on square off-nadir angle proposed in Jason-1 User Handbook document was set to

0.16 deg^2 . Since GDR version "b", this threshold is too restrictive and has to be set to 0.64 deg^2 .

However, this editing criteria had the side effect of removing some bad measurements impacted by rain cells, sigma0 blooms or ice. With the new threshold (0.64 deg^2), these measurements are not rejected any more even though the estimated SSH is not accurate for such waveforms.

Therefore 2 new criteria have to be added to check for data quality :

- Standard deviation on Ku sigma0 \leq 1 dB
- Number measurements of Ku sigma0 \geq 10

The Jason-1 User Handbook suggests the following editing criteria for the version "a" GDRs :

- $-0.2 \text{ deg}^2 \leq$ square of off-nadir angle from waveforms (off_nadir_angle_ku_wvf) \leq 0.16 deg^2
- sigma0_rms_ku < 0.22 dB (optional criterion)

Since the version "b" GDRs these two edit criteria should be replaced by :

- $-0.2 \text{ deg}^2 \leq$ square of off-nadir angle from waveforms (off_nadir_angle_ku_wvf) \leq 0.64 deg^2
- and sigma0_rms_ku \leq 1.0 dB
- and sig0_numval_ku \geq 10

With these new criteria, the editing gives similar results for both product versions. Most of anomalous SSH measurements are rejected. Please note that some of them are still not detected, in particular close to sea ice.

2.5.2. Orbit

The orbit of GDRs "c" uses EIGEN-GL04S gravity field and ITRF2005, instead of EIGEN-CG03C and ITRF2000 for GDRs "b". The change of ITRF induces a North/South bias when comparing with GDRs "b".

2.5.3. Sea state bias

The sea state bias (SSB) model on the GDRs "c" products has been empirically derived from MLE4-retracked altimeter data (cycles 1 to 111, GDRs "b"). Users need to be aware that the SSB model on the GDRs "c" will shift the globally averaged SSH lower by 3-4 cm relative to GDRs "b" (when using SSB from the GDR "b" product). However, figures presented in this report used for GDRs "b" already an updated SSB (computed over cycles 1 to 21 GDRs "b" ; presented at OSTST 2006), which is already quite similar to SSB in GDRs "c" product (approximatively 0.4 cm difference).

2.5.4. Altimeter instrument correction tables

The altimeter instrument correction tables have been updated using a new version of the altimeter simulator. This allows the Jason-1 and Jason-2 altimeter correction tables to be aligned with each other. As a result, altimeter range, SWH, and sigma0 measurements reported on GDRs "c" products are slightly different than the corresponding measurements on GDRs "b", even though identical retracking algorithms (MLE4) were used to generate both products. For more details, see Jason-1 User Handbook.

2.5.5. Jason-1 Radiometer wet troposphere correction

Version "c" GDRs contain the recalibrated JMR data and some improved algorithms to derive JMR brightness temperatures. Time-variable calibration coefficients with new coefficients once per cycle were implemented. There was also a correction of the scale error. As a result of this recalibration a bias of approximately 0.4 cm in the JMR wet path delays exists between the version "b" GDRs from cycle 232 and the version "c" GDRs from cycle 233. This bias will then also affect mean SSH at this transition when JMR wet path

delays are used to compute SSH. A JMR replacement product that contains recalibrated JMR wet path delay measurements for cycles that are being reprocessed into version "c" (e.g. cycles < 233) was already released (ftp://podaac.jpl.nasa.gov/pub/sea_surface_height/jason/jmr_replacement). This replacement product can be used to ensure a stable sea surface height time series for precision applications such as mean sea level monitoring.

3. Poseidon-2 altimeter and sensor

3.1. Sensor status

A detailed assessment of the Poseidon-2 sensor is made in a separate bulletin to be made available on request.

3.2. Poseidon-2 altimeter status

This section presents the general status of the altimeter for main instrumental variations through the Jason-1 mission. Two calibration modes are used to monitor the altimeter internal drifts and compute the altimetric parameters. They are programmed about three times per day, over land.

The CAL1 mode measures the Point Target Response (PTR) of the altimeter in Ku and C bands. Among the parameters extracted from the PTR are :

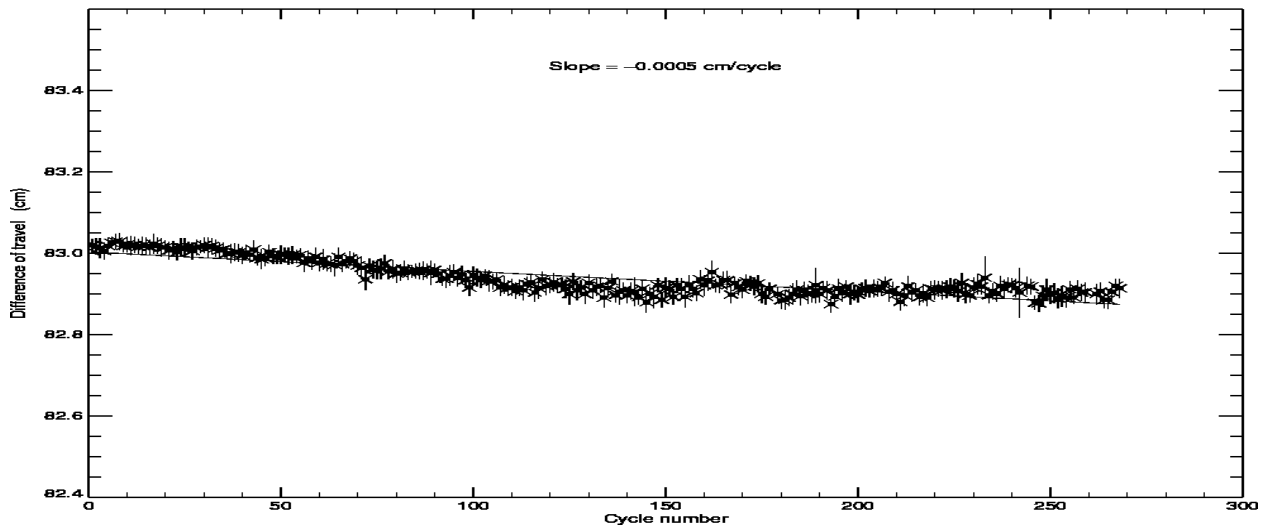
- the internal path delay
- the total power of the PTR

The evolutions of these parameters as a function of time are plotted to monitor the ageing of the altimeter. Notice that in the Jason-1 products, the range is corrected for the internal path delay and the backscatter coefficient takes into account the total power of the measured PTR.

3.2.1. Monitoring of the internal path delay

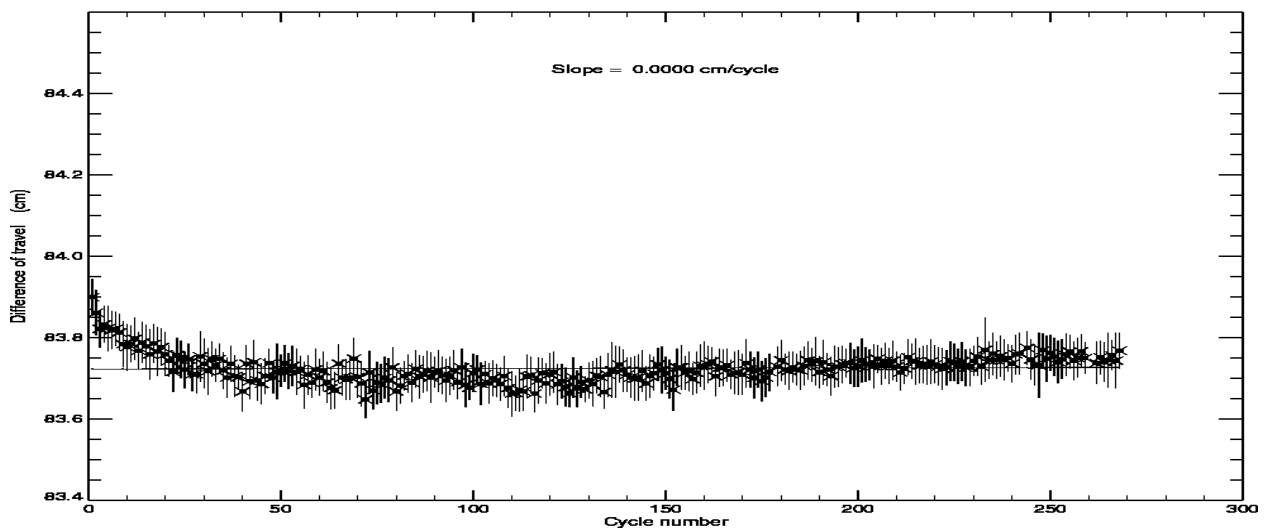
POSEIDON2 – Cycle 001 to Cycle 268

Difference of travel between E and R lines of the PTR in Ku band



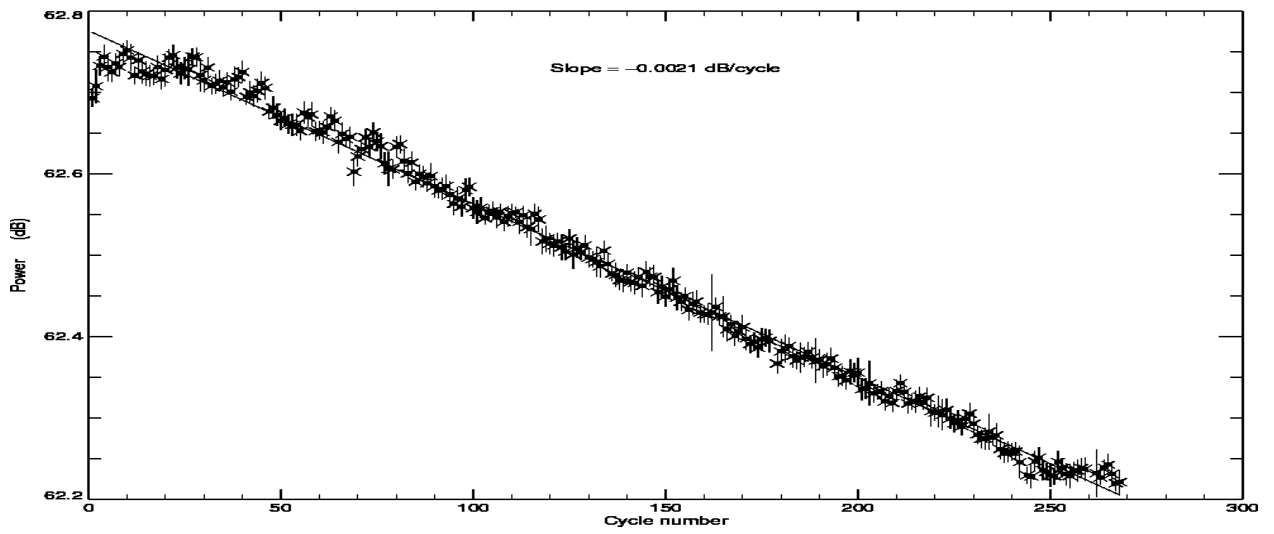
POSEIDON2 – Cycle 268

Difference of travel between E and R lines of the PTR in C band

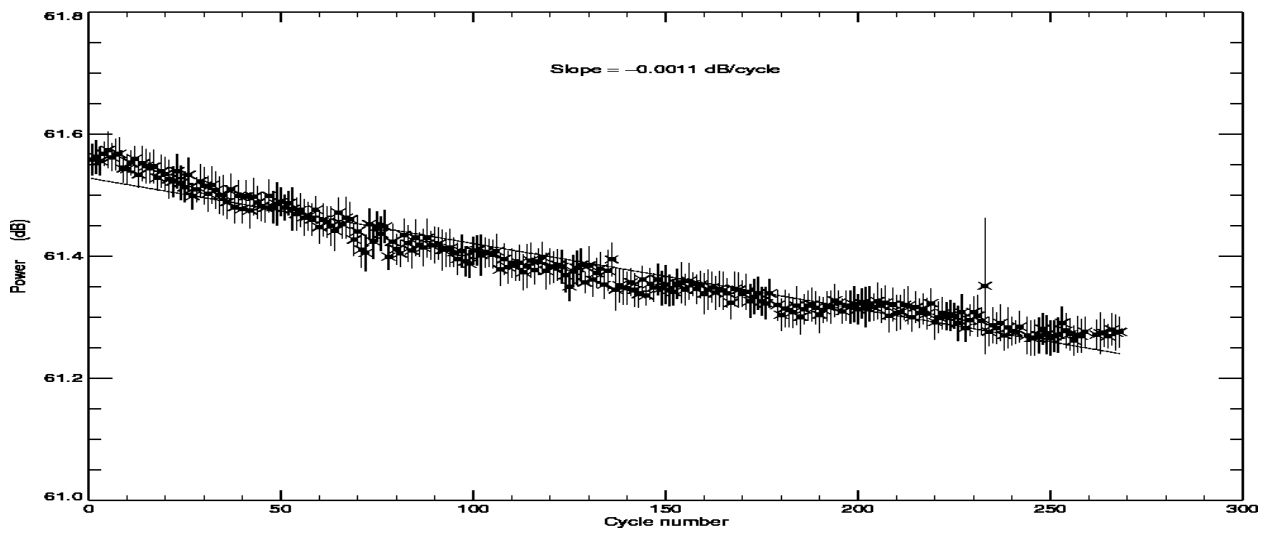


3.2.2. Monitoring of the total power in the PTR

POSEIDON2 – Cycle 268
Total power of the PTR in Ku band



POSEIDON2 – Cycle 268
Total power of the PTR in C band

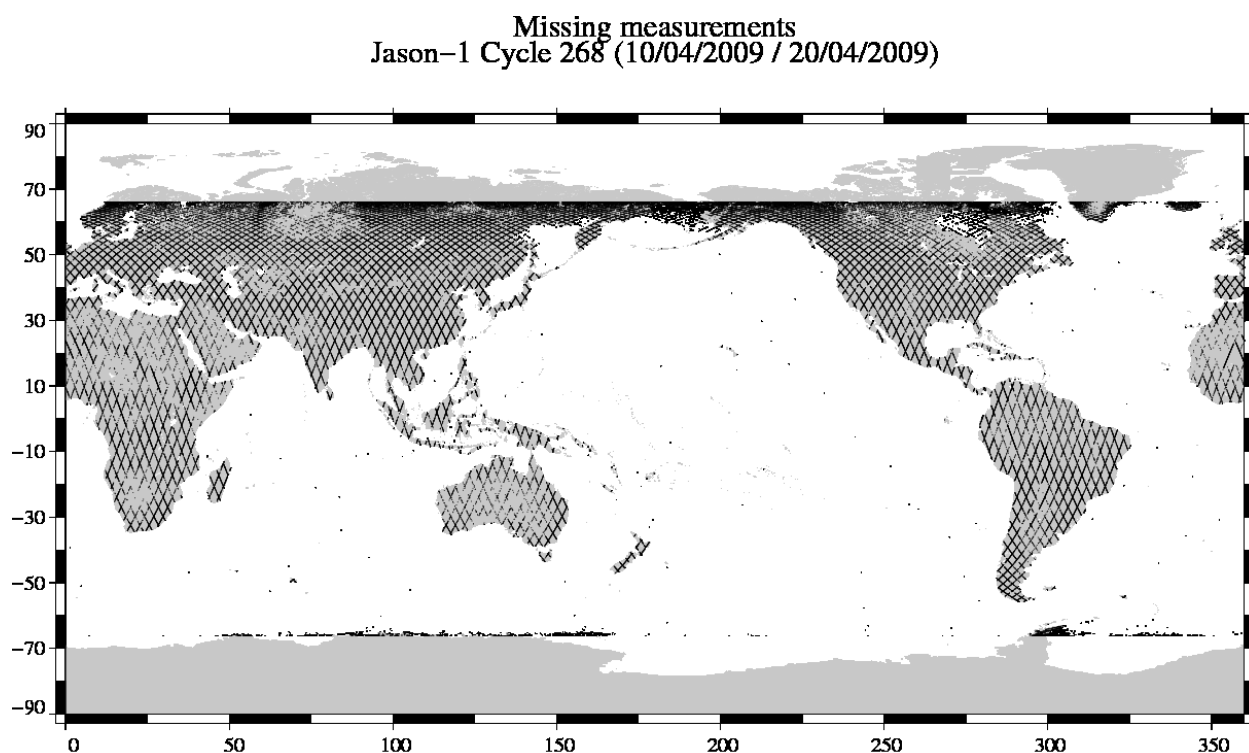


4. CALVAL main results

This section presents results that illustrate data quality during this cycle. These verification products are produced operationally so that they allow systematic monitoring of the main relevant parameters.

4.1. Missing measurements

The map below illustrates missing 1Hz measurements in the GDRs, with respect to a 1 Hz sampling of a nominal repeat track.



4.2. Edited measurements

Editing criteria are defined for the GDR product in Aviso and PODAAC User Handbook [2].

The editing criteria are defined as minimum and maximum thresholds for various parameters. Measurements are edited if at least one parameter does not lie within those thresholds. These thresholds are expected to remain constant throughout the Jason-1 mission, so that monitoring the number of edited measurements allows a survey of data quality.

In the following, only measurements over ocean are kept. This is done by applying an ocean-land mask, instead of using the altimeter state flag (*alt_state_flag*) or the radiometer state flag (*rad_state_flag*). There is no impact on global performance estimations since the more significant results are derived from analyses in open ocean areas.

The rain flag is not used for data selection.

The number and percentage of points removed by each criterion is given on the following table. Note that these statistics are obtained with measurements already edited for ice flag (5.86 % of points removed).

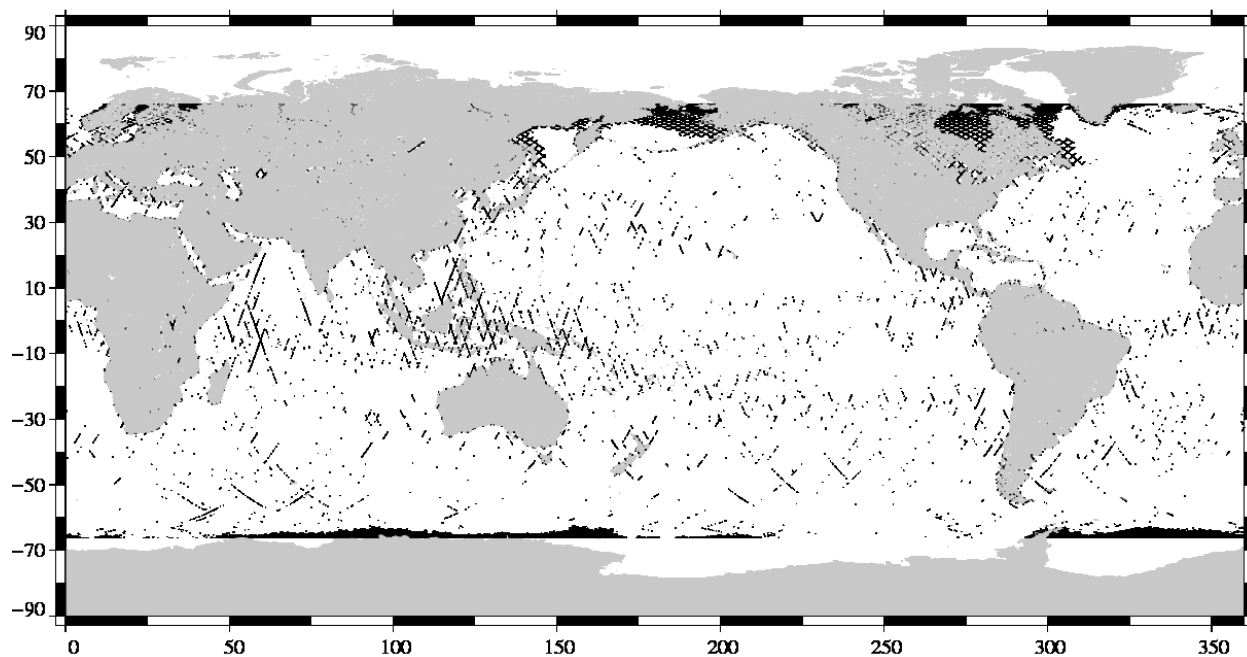
Concerning GDR in version B (cycles 1 - 232), instead of the ice flag available in the GDR, an ice flag similar to ERS ice flag was used. It takes into account the difference between (dualfrequency) radiometer and ecmwf model wet troposphere correction. It has the advantage to better detect sea ice in the Hudson Bay, which was previously only removed by the other parameters. Since GDR version C (cycle 233 and onwards), this ice flag is already available in the products, and therefore used for the editing.

| Parameters | Min threshold | Max threshold | Unit | Nb removed | % removed | % mean removed |
|--|---------------|---------------|--------------------------|------------|-----------|----------------|
| Sea surface height | -130.000 | 100.000 | <i>m</i> | 4257 | 0.77 | 0.75 |
| Sea level anomaly | -2.000 | 2.000 | <i>m</i> | 4818 | 0.87 | 1.40 |
| Nb measurements of range | 10.000 | – | – | 6151 | 1.11 | 1.09 |
| Std. deviation of range | 0.000 | 0.200 | <i>m</i> | 7172 | 1.30 | 1.28 |
| Square off nadir angle | -0.200 | 0.640 | <i>deg</i> ² | 2758 | 0.50 | 0.48 |
| Dry tropospheric correction | -2.500 | -1.900 | <i>m</i> | 0 | 0.00 | 0.00 |
| Combined atmospheric correction | -2.000 | 2.000 | <i>m</i> | 0 | 0.00 | 0.00 |
| JMR wet tropospheric correction | -0.500 | -0.001 | <i>m</i> | 195 | 0.04 | 0.17 |
| Ionospheric correction | -0.400 | 0.040 | <i>m</i> | 5820 | 1.05 | 1.08 |
| Significant wave height | 0.000 | 11.000 | <i>m</i> | 3140 | 0.57 | 0.55 |
| Sea State Bias | -0.500 | 0.000 | <i>m</i> | 2686 | 0.49 | 0.91 |
| Backscatter coefficient | 7.000 | 30.000 | <i>dB</i> | 2827 | 0.51 | 0.51 |
| Nb measurements of sigma0 | 10.000 | – | – | 6082 | 1.10 | 1.08 |
| Std. deviation of sigma0 | 0.000 | 1.000 | <i>dB</i> | 8711 | 1.57 | 1.61 |
| Ocean tide | -5.000 | 5.000 | <i>m</i> | 230 | 0.04 | 0.04 |
| Equilibrium tide | -0.500 | 0.500 | <i>m</i> | 0 | 0.00 | 0.00 |
| Earth tide | -1.000 | 1.000 | <i>m</i> | 0 | 0.00 | 0.00 |
| Pole tide | -15.000 | 15.000 | <i>m</i> | 0 | 0.00 | 0.00 |
| Altimeter wind speed | 0.000 | 30.000 | <i>m.s</i> ⁻¹ | 5241 | 0.95 | 0.91 |
| Global statistics of edited measurements by thresholds | – | – | – | 15293 | 2.76 | 2.94 |

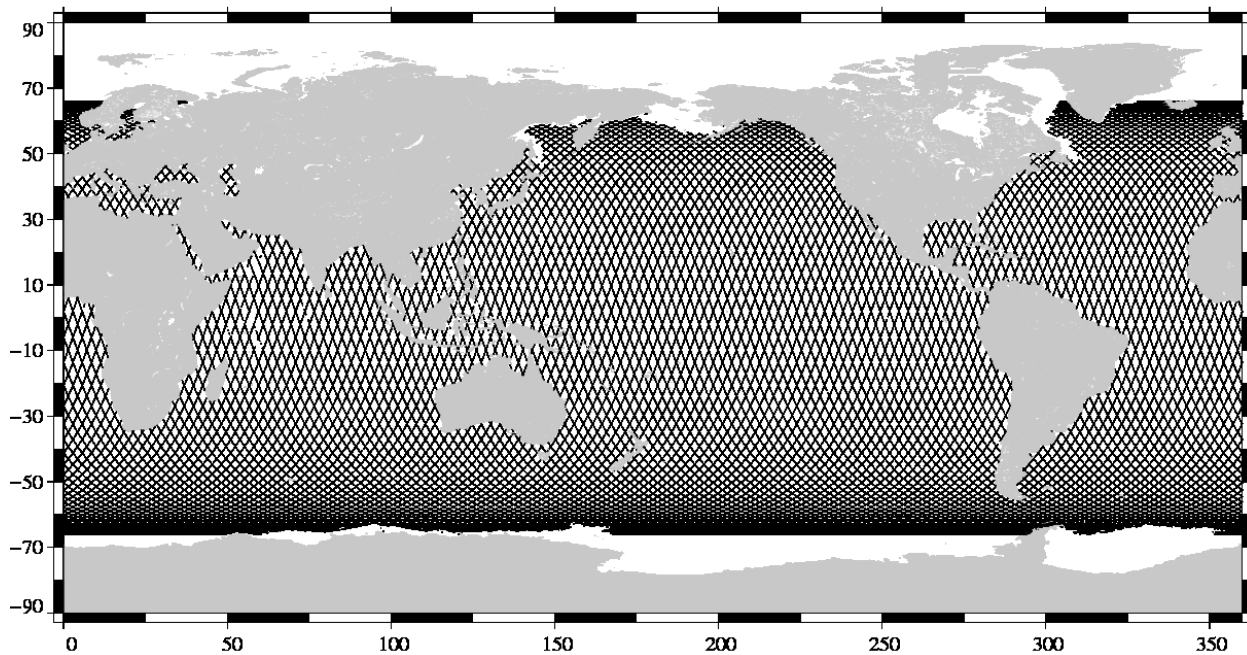
4.2.1. Figures

The following two maps are complementary : they show respectively the removed and selected measurements in the editing procedure.

Edited measurements
Jason-1 Cycle 268 (10/04/2009 / 20/04/2009)

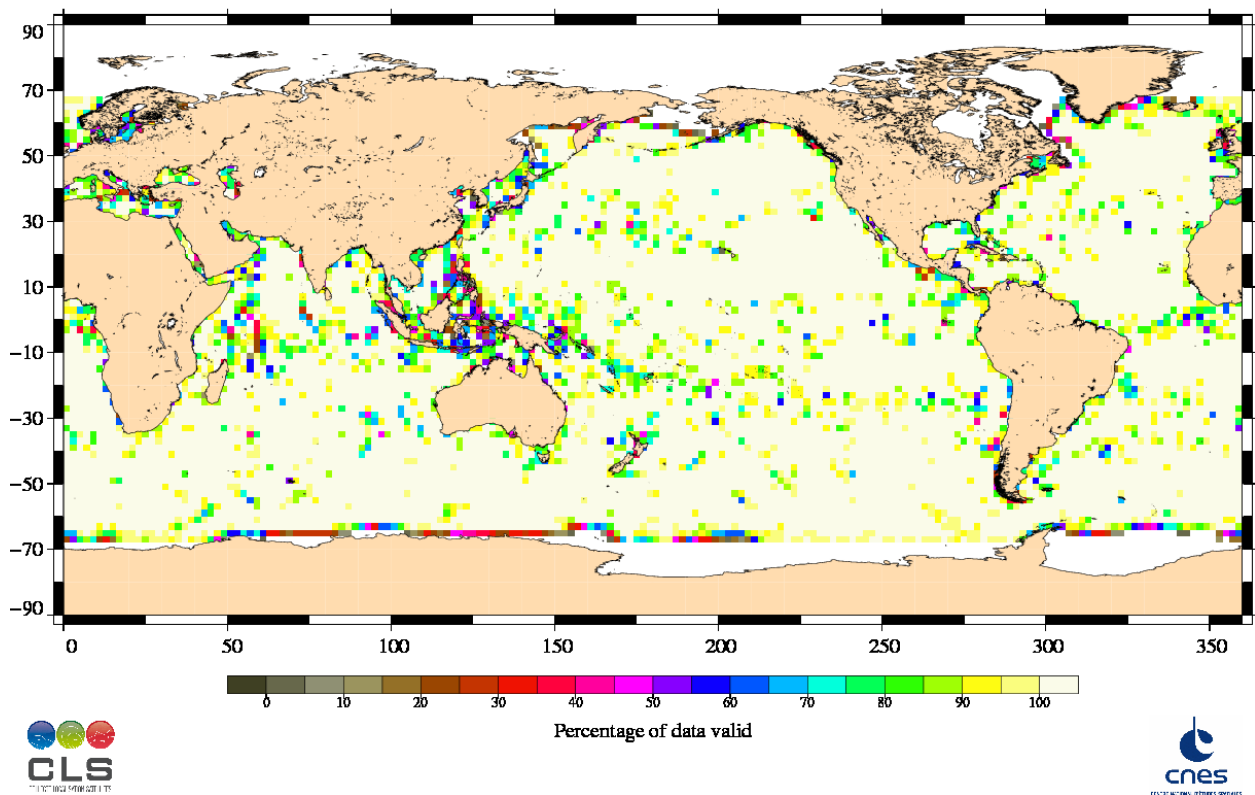


Valid data
Jason-1 Cycle 268 (10/04/2009 / 20/04/2009)



The next map shows the percentage of valid measurements by sample.

Percentage of valid data relative to the nominal pass
Jason-1 Cycle 268 (10/04/2009 / 20/04/2009)

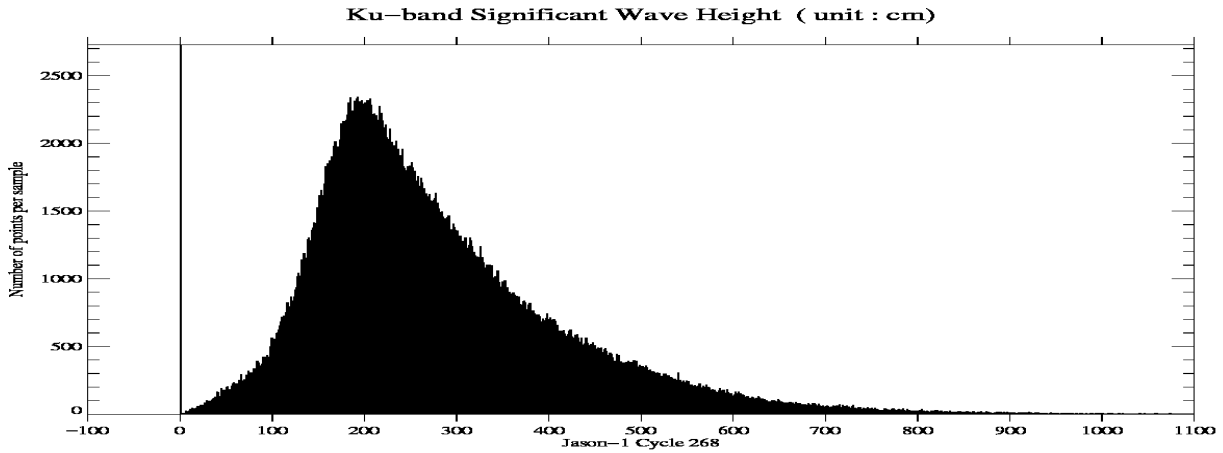



4.2.2. Comments

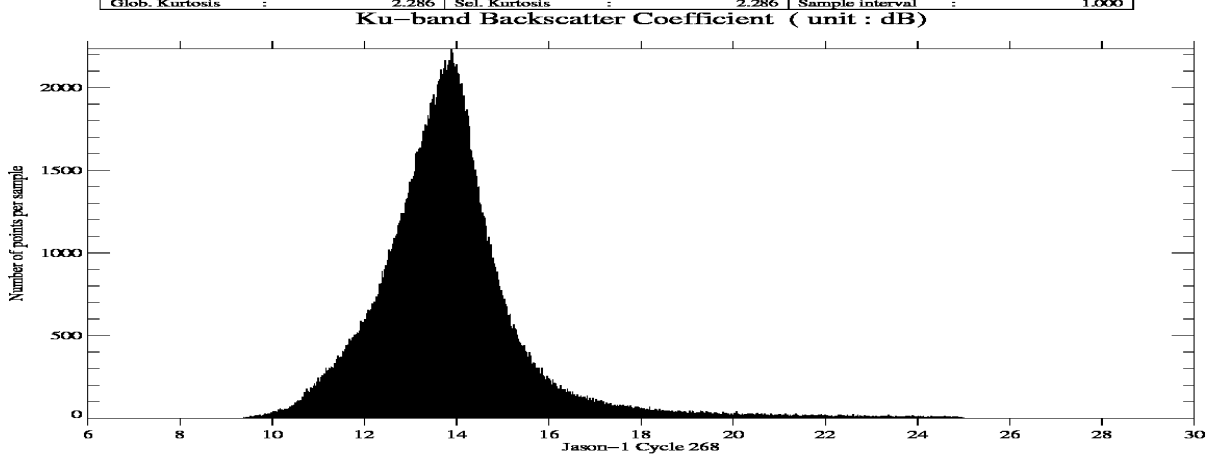
Wet zones appear in the plot of removed data, as it was also the case for Topex and Poseidon altimeters : measurements may be corrupted by rain. Compared with the usual maps obtained for Topex, there are less removed data in these zones and in the areas of strong sea states.


4.3. Altimeter parameters

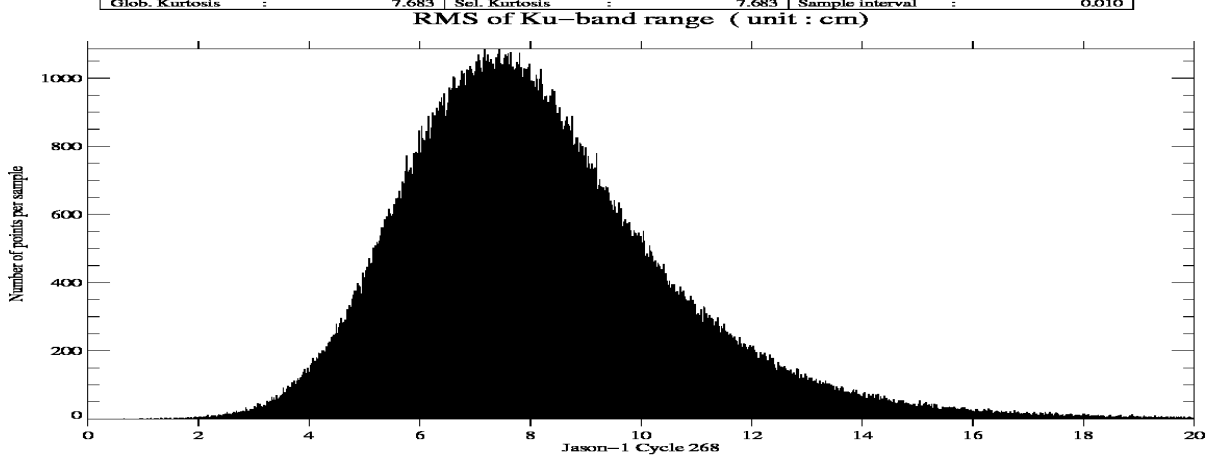
In order to assess and to monitor altimeter parameter measurements, histograms of Jason-1 Ku-band Significant Wave Height (SWH), Backscatter coefficient (Sigma0) and RMS of altimeter range are computed for the valid data set previously defined.




| | | | | | | |
|---|-------------------|---------|------------------|---------|-------------------|----------|
|  | Glob. Nb of pts : | 538081 | Sel. Nb of pts : | 538081 | Glob. Maximum : | 1099.800 |
| | Glob. Mean : | 276.450 | Sel. Mean : | 276.450 | Glob. Minimum : | 0.000 |
| | Glob. Std : | 137.159 | Sel. Std : | 137.159 | Sel. Maximum : | 1099.800 |
| | Glob. Skewness : | 1.217 | Sel. Skewness : | 1.217 | Sel. Minimum : | 0.000 |
| | Glob. Kurtosis : | 2.286 | Sel. Kurtosis : | 2.286 | Sample interval : | 1.000 |



| | | | | | | |
|---|-------------------|--------|------------------|--------|-------------------|--------|
|  | Glob. Nb of pts : | 538081 | Sel. Nb of pts : | 538081 | Glob. Maximum : | 25.000 |
| | Glob. Mean : | 13.828 | Sel. Mean : | 13.828 | Glob. Minimum : | 9.380 |
| | Glob. Std : | 1.630 | Sel. Std : | 1.630 | Sel. Maximum : | 25.000 |
| | Glob. Skewness : | 1.796 | Sel. Skewness : | 1.796 | Sel. Minimum : | 9.380 |
| | Glob. Kurtosis : | 7.683 | Sel. Kurtosis : | 7.683 | Sample interval : | 0.010 |



| | | | | | | |
|---|-------------------|--------|------------------|--------|-------------------|--------|
|  | Glob. Nb of pts : | 538081 | Sel. Nb of pts : | 538075 | Glob. Maximum : | 20.000 |
| | Glob. Mean : | 8.114 | Sel. Mean : | 8.114 | Glob. Minimum : | 0.650 |
| | Glob. Std : | 2.393 | Sel. Std : | 2.393 | Sel. Maximum : | 19.990 |
| | Glob. Skewness : | 0.870 | Sel. Skewness : | 0.870 | Sel. Minimum : | 0.650 |
| | Glob. Kurtosis : | 1.412 | Sel. Kurtosis : | 1.408 | Sample interval : | 0.010 |



4.4. Radiometer parameters

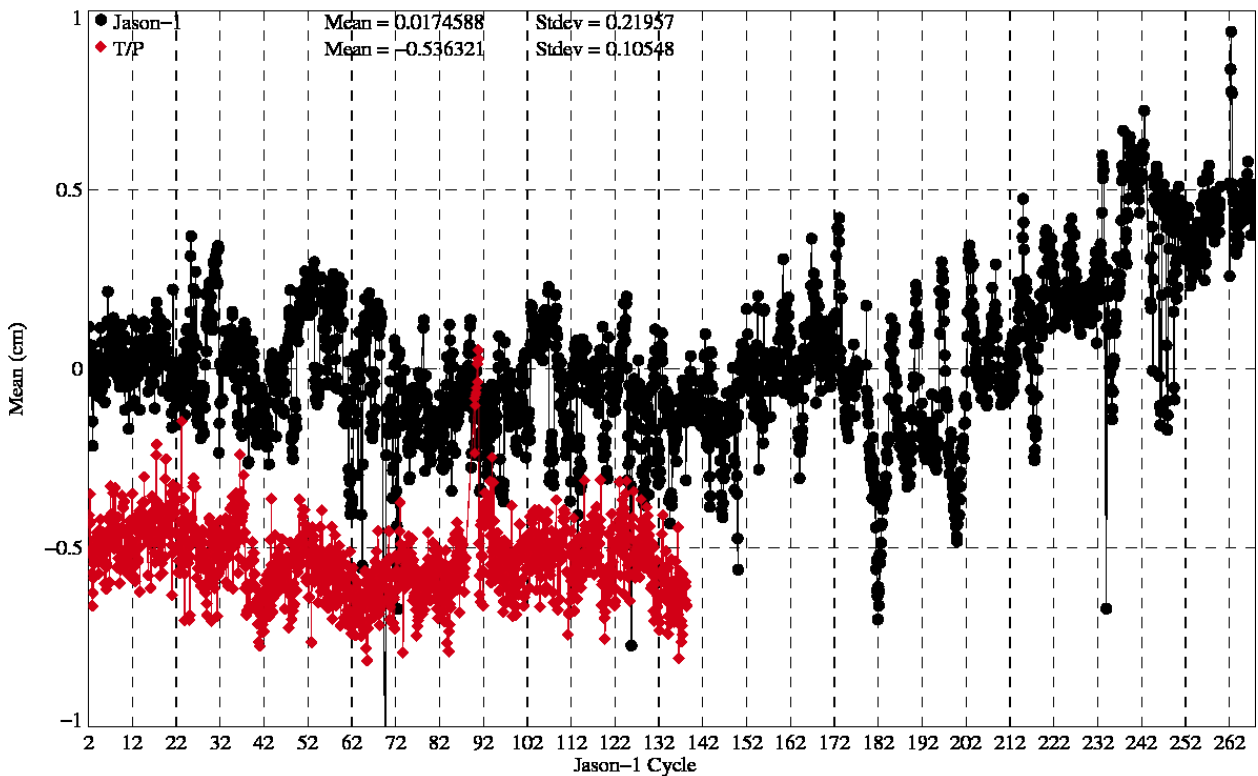
Daily mean of (Radiometer - ECMWF) wet troposphere corrections is plotted below for Jason-1 and T/P. Note that the TMR correction has been corrected for the drift (Sharroo R. et al., 2004 [4]). Moreover the 60-day signal due to TOPEX yaw maneuvers has been partially removed. Since 9th October 2005 scientific mission of TOPEX has stopped.

JMR wet troposphere correction in GDR version "a", used to show a 60-day signal due to Jason-1 yaw maneuvers, as well as jumps. These anomalies are now corrected in the GDR version "b". Nevertheless this long term monitoring exhibits still abnormal variations :

- The 60-day signals due to Jason-1 yaw maneuvers is sometimes still visible.
- After the safhold mode (during cycles 177 to 179), JMR-ECMWF wet troposphere correction decreases about 7 mm, before coming back to normal. In the following it continues to be influenced by yaw maneuvers.

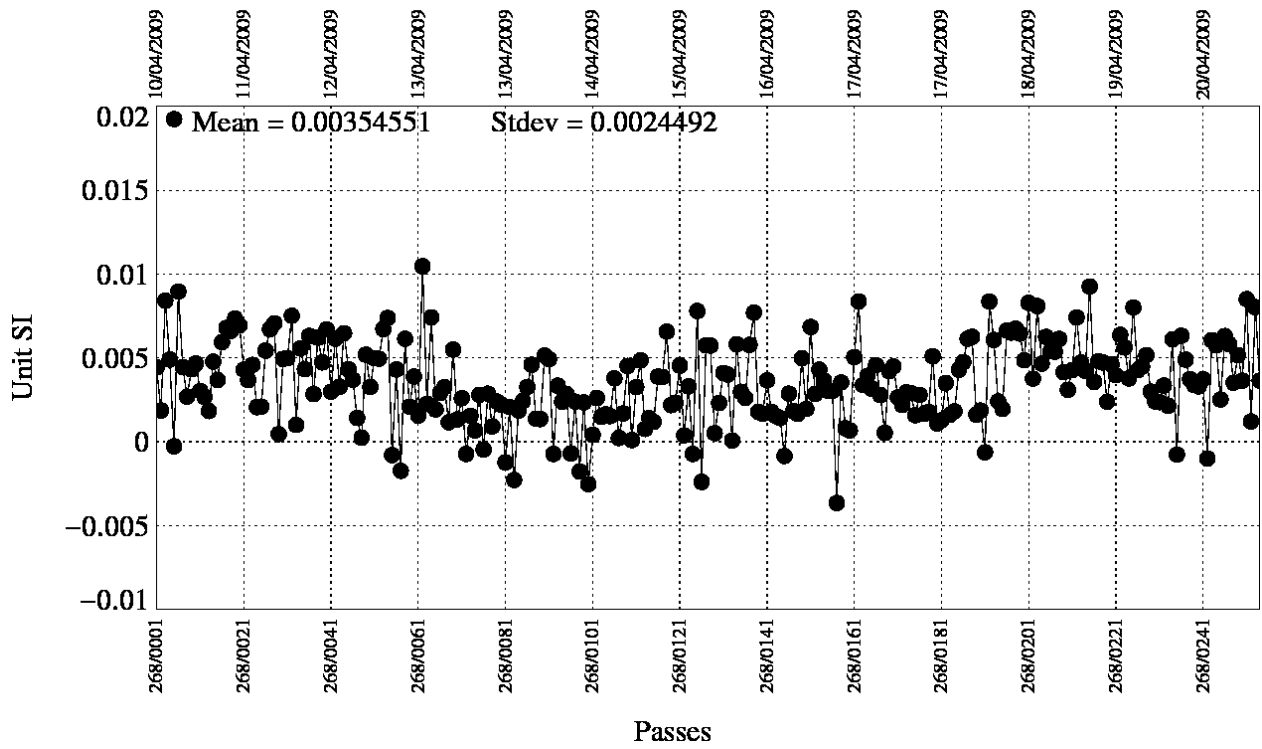
Since cycle 233, JMR wet troposphere correction of GDR version "c" is used.

(Radiometer – ECMWF) wet tropo correction



The figure below shows the mean of wet troposphere correction (radiometer - ECMWF) difference by pass.

Mean of D_TROPO by pass

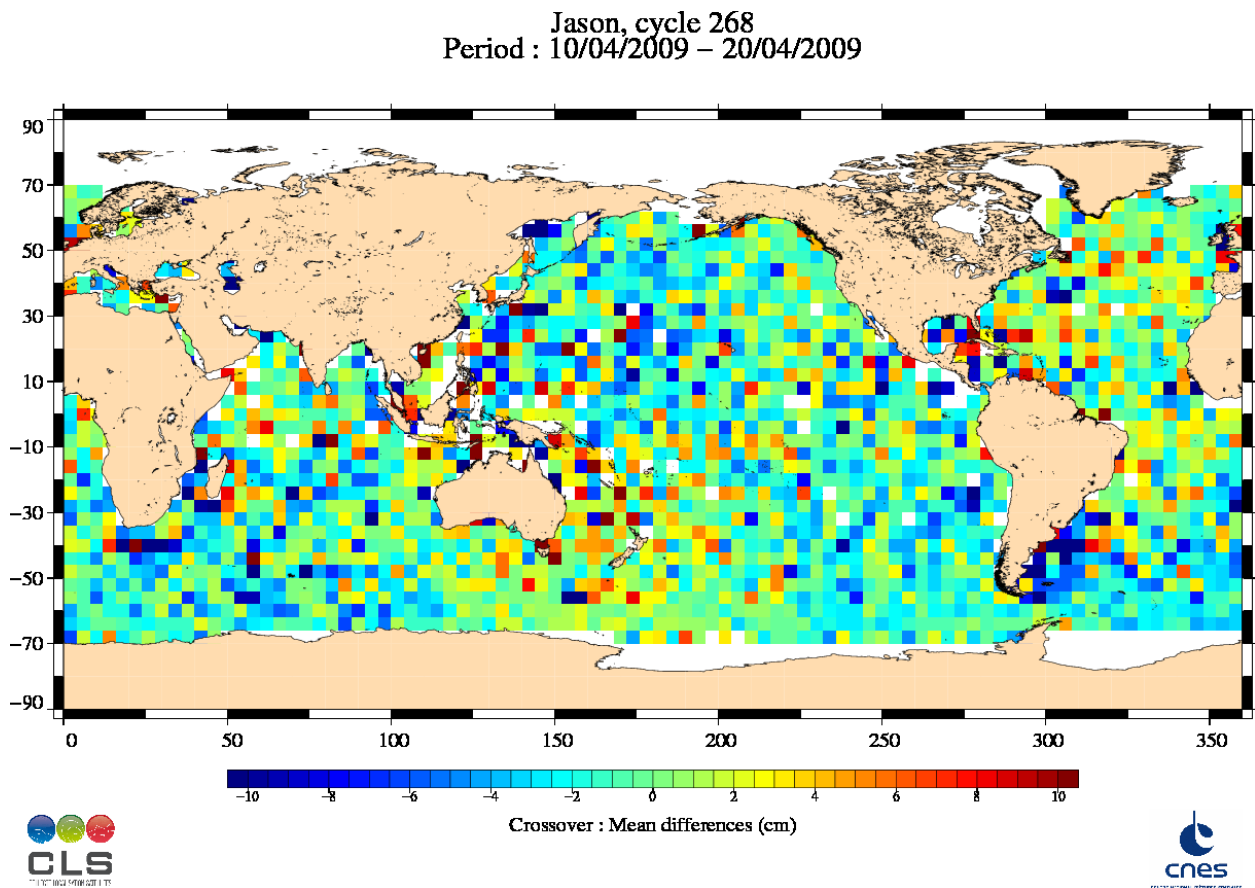


4.5. Crossover statistics

SSH crossover statistics are computed from the valid data set. They are used to estimate the data quality and to monitor the system performances.

After data editing and using the standard Jason-1 algorithms, the crossover standard deviation is about 5.30 cm rms, when using a selection to remove shallow waters (1000 m), areas of high ocean variability and high latitudes ($> |50|$ deg.).

The map of the mean differences at crossovers (4 by 4 degrees by bins) is plotted below.

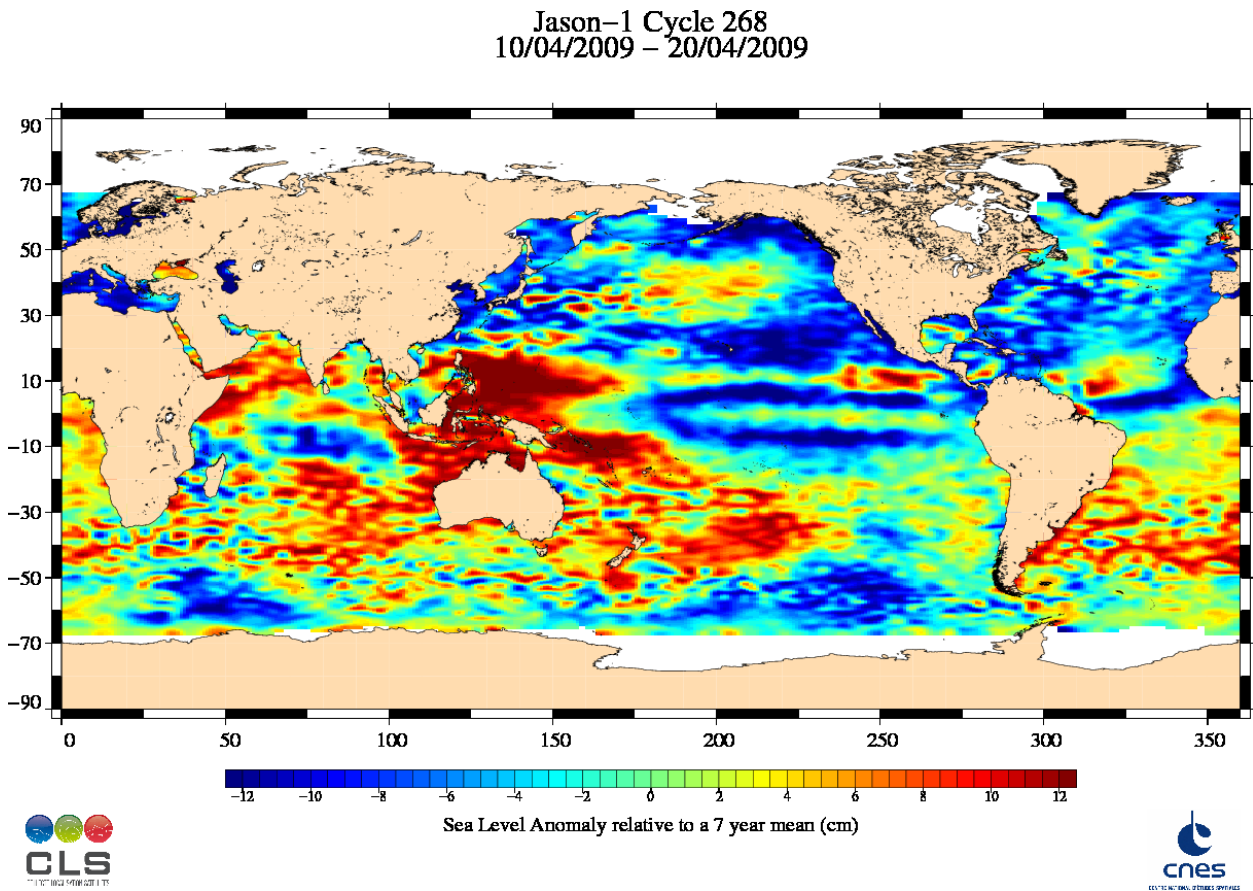


4.6. SSH variability

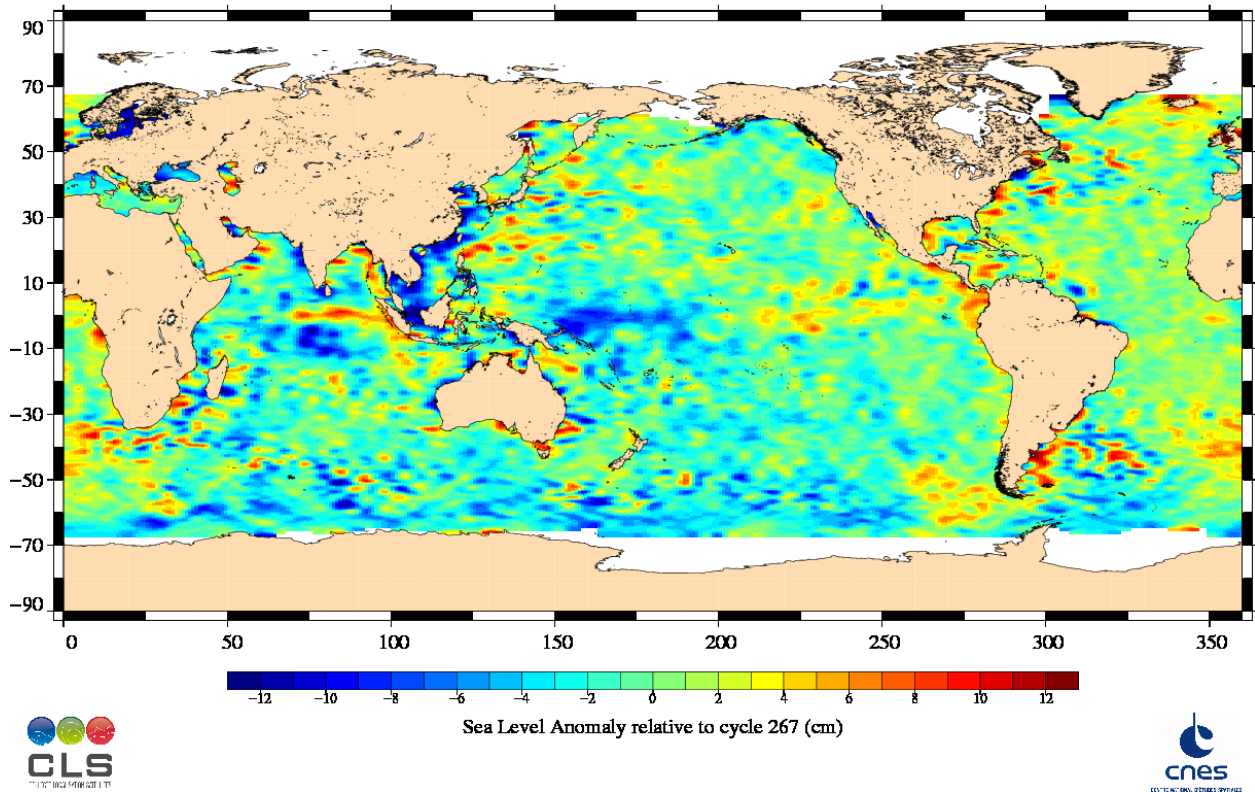
4.6.1. Jason-1 Sea Level Anomalies

Repeat-track analysis is routinely used to compute Sea Level Anomalies (SLA) relative to the previous cycle and relative to a mean profile. SLA relative to a 7-year mean (based on TOPEX/Poseidon data) shows general oceanic features in good agreement with what is observed with TOPEX/Poseidon.

The SSH differences relative to the previous cycle 267 are plotted on the bottom figure. The differences seem homogeneous and do not exhibit any particular trackiness pattern, showing the good quality of the orbit calculation in the Jason-1 GDRs.



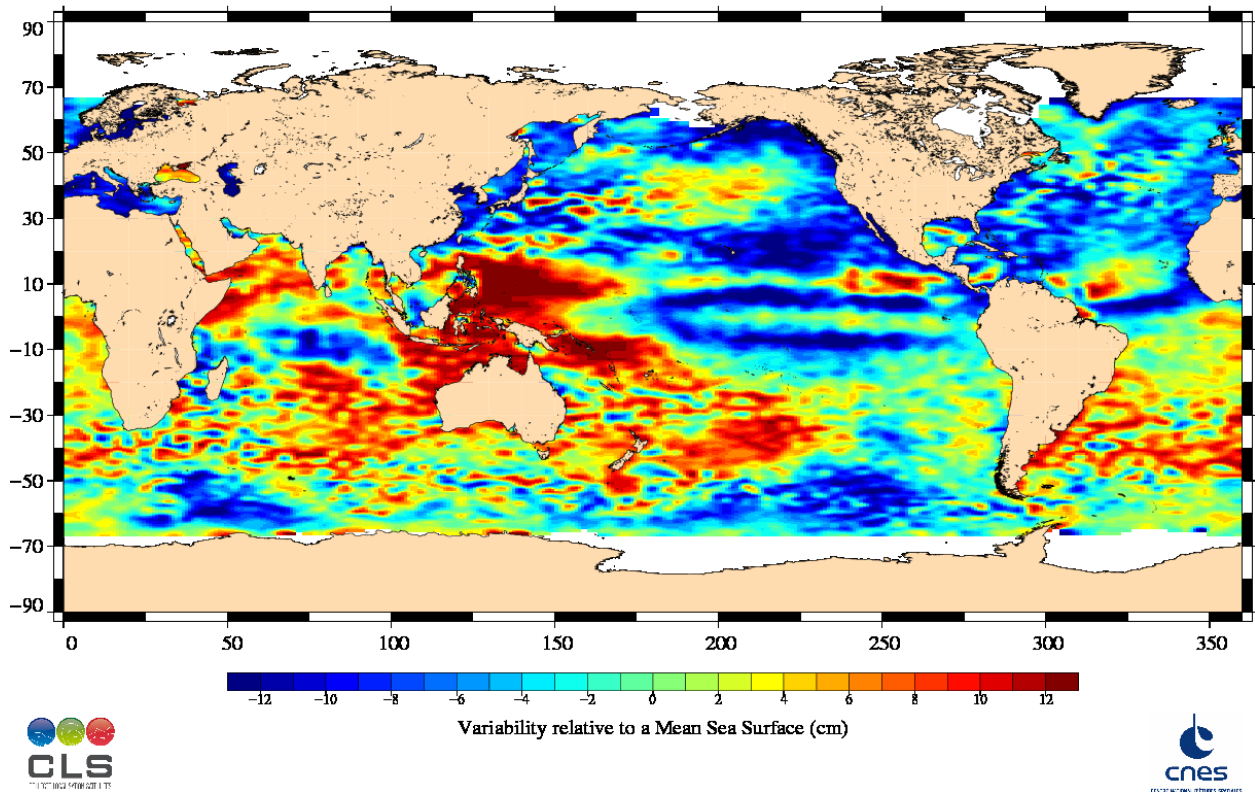
Jason-1 Cycle 268
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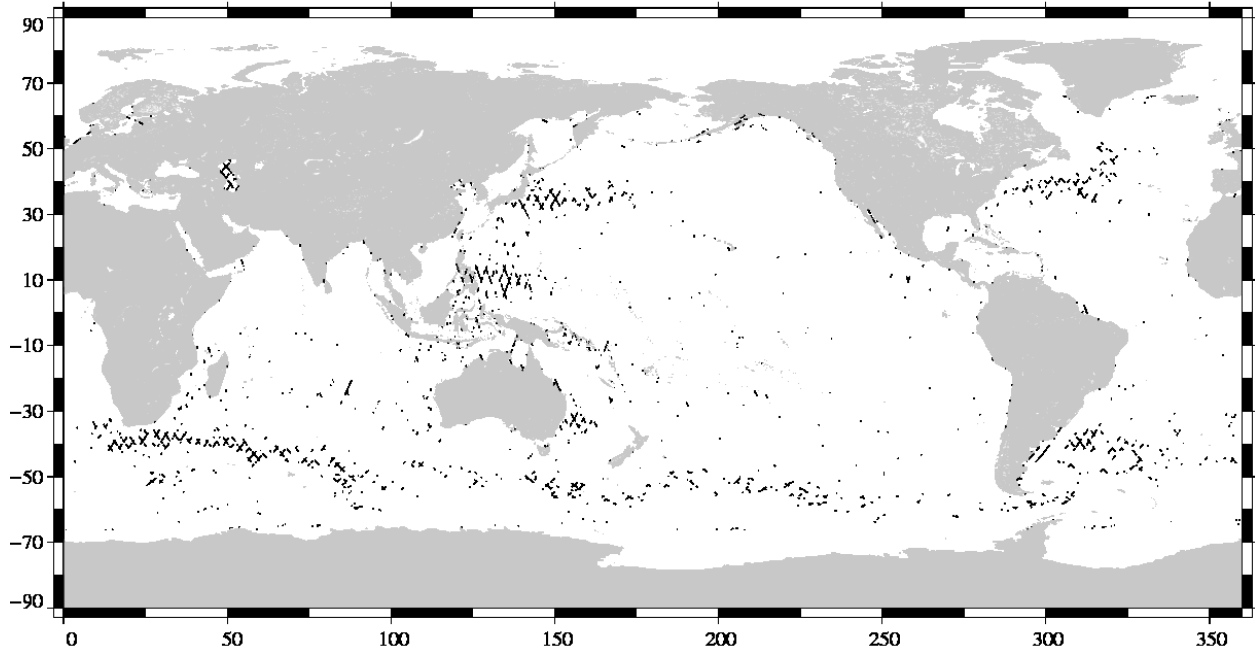
4.6.2. Comparison to a Mean Sea Surface

The following two maps respectively show the map of Jason-1 SLA relative to the MSS and differences higher than a 30 cm threshold (after centering the data). The latter figure shows that apart from isolated measurements that should be removed after refining the editing thresholds, higher differences are located in high ocean variability areas, as expected.

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10/04/2009 – 20/04/2009



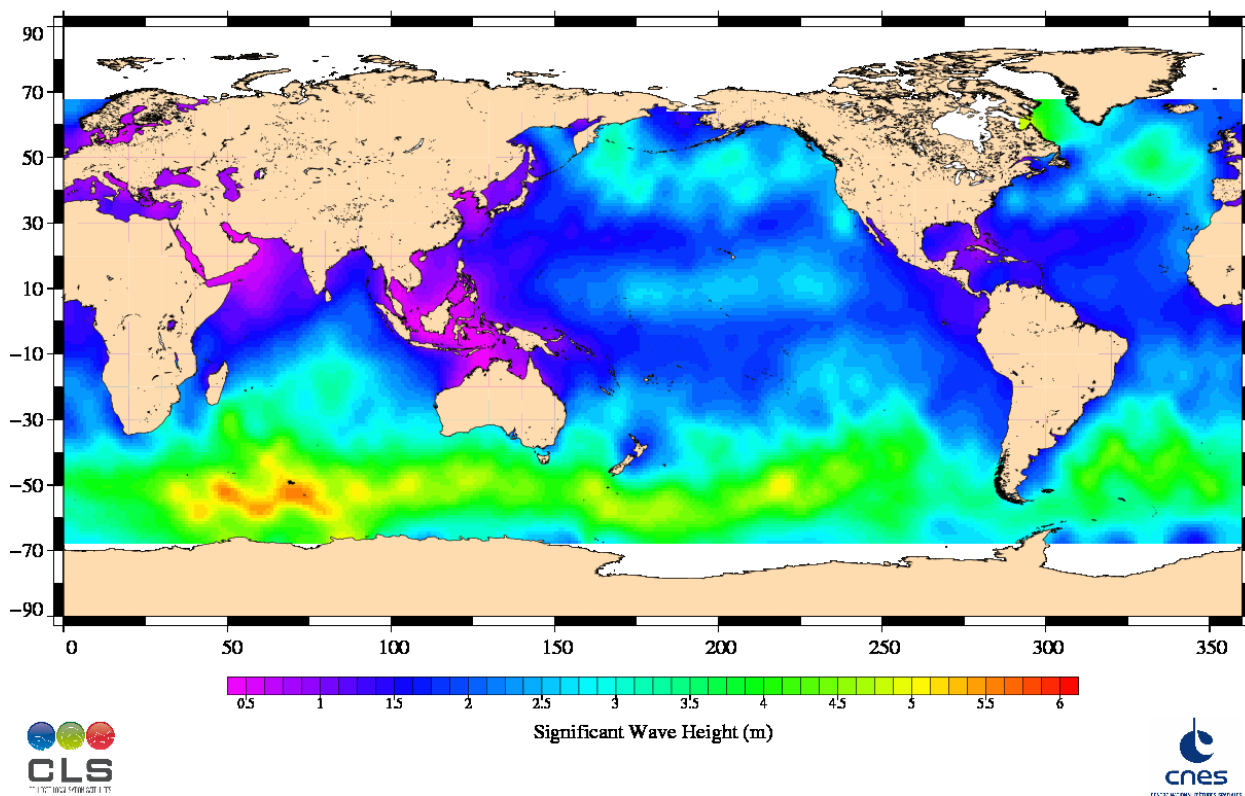
(SSH - MSS) differences greater than 30 cm
Jason / Cycle 268



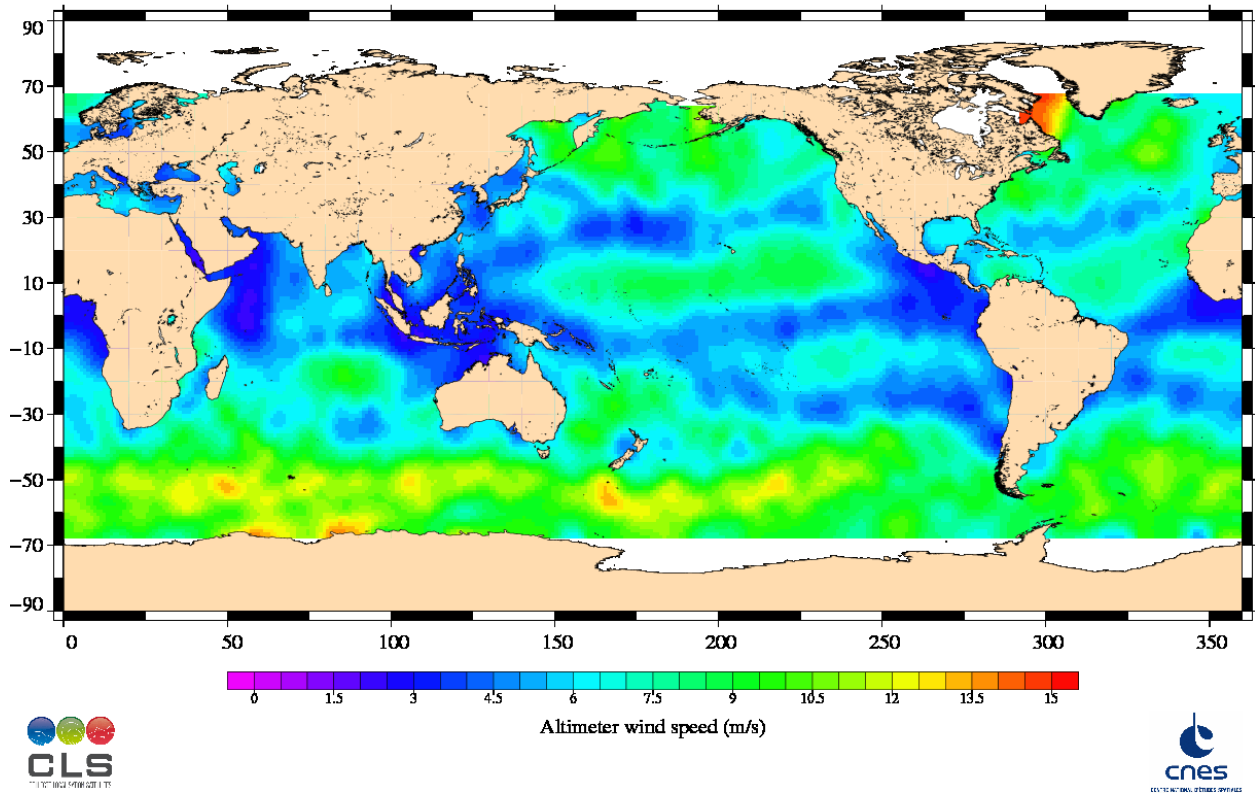
4.7. Wind and wave maps

These two figures show wind and wave estimations derived from 10 days of altimeter measurements.

Jason-1 Cycle 268
10/04/2009 – 20/04/2009



Jason-1 Cycle 268
10/04/2009 – 20/04/2009



5. Jason-1 long term performance monitoring

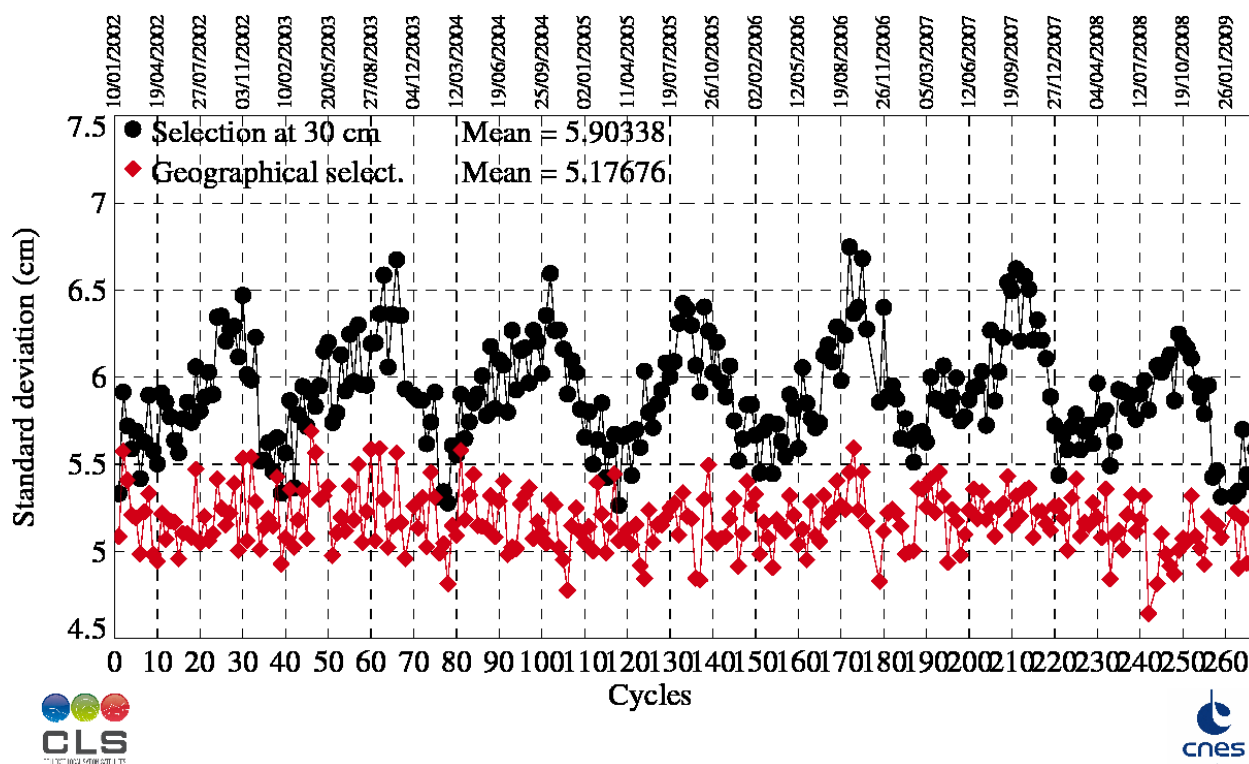
Statistics of SSH variability are computed after crossover and repeat-track analyses. This allows to estimate how Jason-1 data fulfill the mission objectives in terms of performances.

5.1. Standard deviation of the differences at crossovers

This parameter is plotted as a function of time in a one cycle per cycle basis in the figure below. It is computed after data editing and using 2 additional selection criteria :

- Selecting crossover differences lower than 30 cm to avoid contamination by remaining spurious data.
- Removing shallow waters (1000 m), areas of high ocean variability and high latitudes ($> |50|$ deg.) to avoid ice coverage effects.

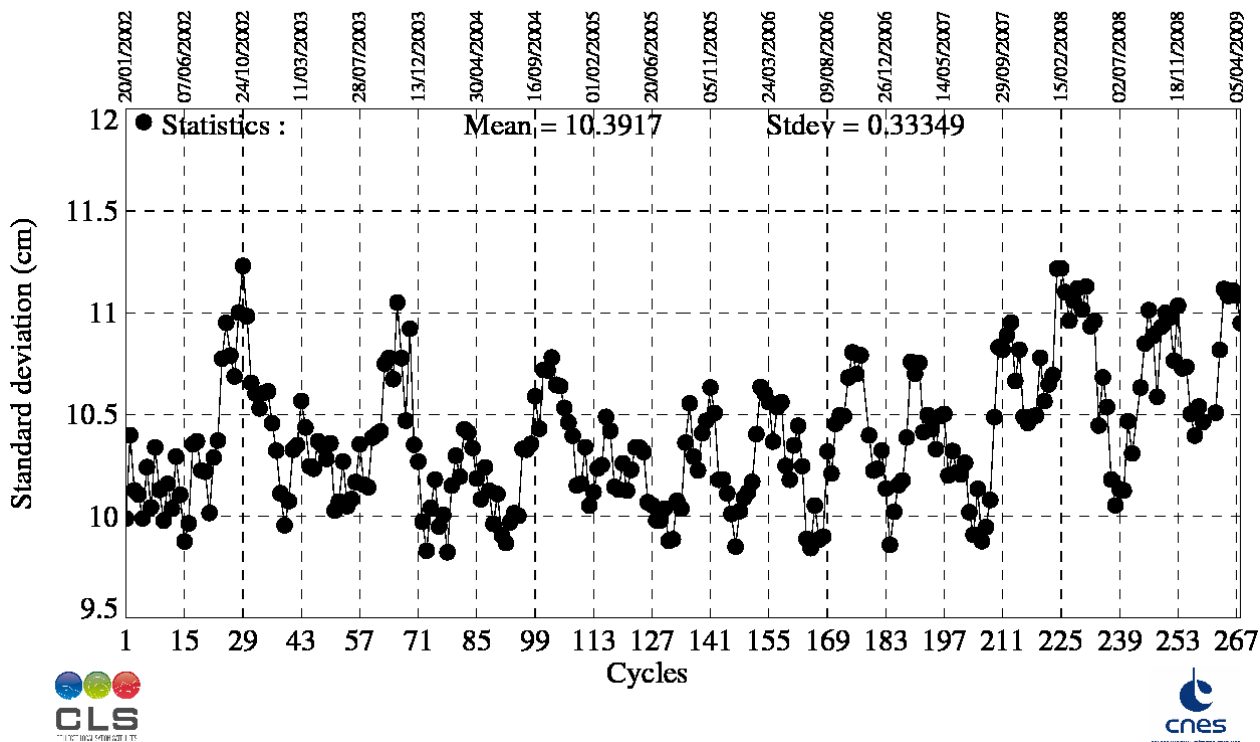
Crossover standard deviation



5.2. RMS of Sea Level Anomaly

Sea Level Anomalies relative to a mean profile are computed using repeat-track analysis for each Jason-1 cycle. To monitor Jason-1 performances and ocean signals, the cycle per cycle standard deviation of the SLA is plotted as a function of time.

Standard deviation of Sea Level Anomalies

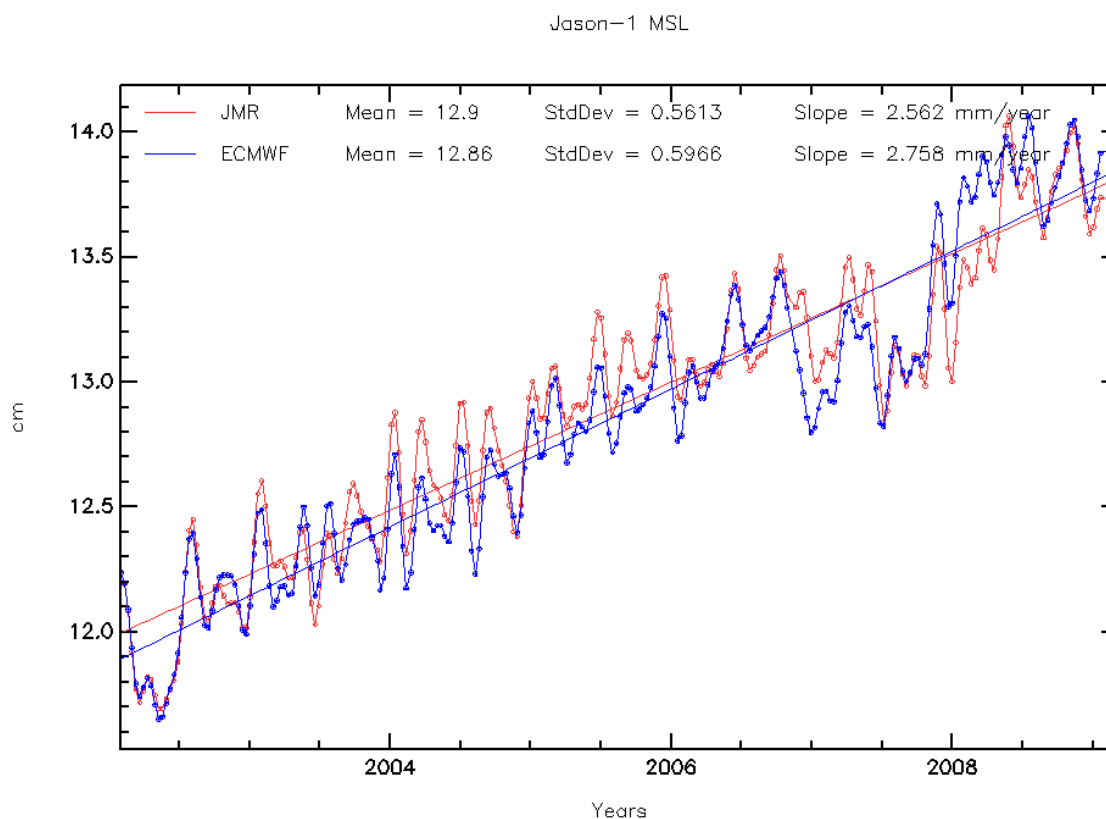


6. Mean Sea Level estimations (MSL)

6.1. Jason-1 MSL

MSL estimations are performed in a cycle basis averaging Sea Level Anomalies relative to a mean profile. The value for each cycle is calculated from averaging over 2 by 3 degree bins, then weighting by latitude to take into account the relative geographical area represented by the bin. Results plotted on the following figure are obtained after annual, semi-annual and 60-day signals reduction. MSL estimations are computed with JMR or ECMWF wet troposphere correction so as to compare both solutions. Indeed wet troposphere correction is a main source of error for the MSL calculation. During the GDR-C reprocessing phase (ongoing), MSL calculations use version B from cycles 1 to 232, and version C from cycle 233 onward. To correct for the bias induced by this change of version, a bias map has been applied, calculated on the MSL differences observed between versions B and C for cycles 229 to 232, showing a very good linking of the series. When the reprocessing is over, the whole time series will be available in version C and there will be no need for this bias map any longer. Users are strongly advised to refer to the estimated MSL provided on the AVISO website (<http://www.aviso.oceanobs.com/msl>). Details of the way MSL trends are computed are described in [7].

End of 2007, beginning of 2008, in relationship with a version change of the ECMWF model, there is a discrepancy visible between the two wet troposphere corrections.



7. Particular investigations

No particular investigations have been performed on this cycle.

- [1] Picot N., October 21, 2005 : New Jason-1 operational production chain. *Electronic communication*.
- [2] Aviso and PODAAC User Handbook, April 2003 : IGDR and GDR Jason User Products, *SMM-MU-M5-OP-13184-CN*.
- [3] Gaspar, P., S. Labroue & F. Ogor, October 2002 : Improving nonparametric estimates of the sea state bias in radar altimeter measurements of sea level *J. Atmos. Oceanic Technol.*, **19**, 1690-1707.
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