

# The new ITSG-Grace2016 release

**Matthias Ellmer, Torsten Mayer-Gürr, Saniya Behzadpour, Beate Klinger, Andreas Kvas, and Norbert Zehentner**

Institute of Geodesy  
NAWI Graz, Graz University of Technology

AOGS 2016, Beijing

# Outline

- Methods, Models
- Processing details
- Unconstrained monthly solutions
- Summary & Conclusions

# ITSG-Grace2016

## Method:

- Variational equations
- 24h arc length
- 3h covariance length

## Input:

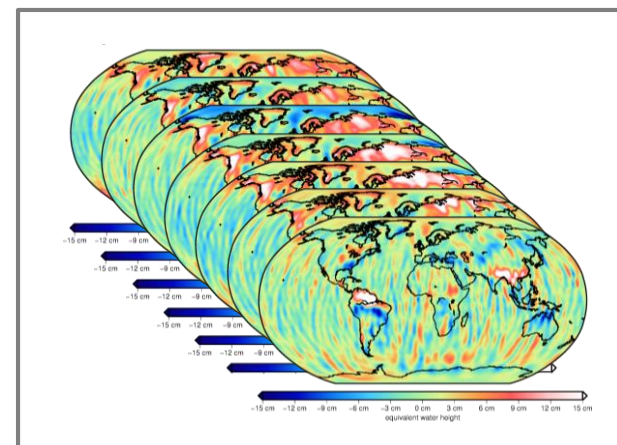
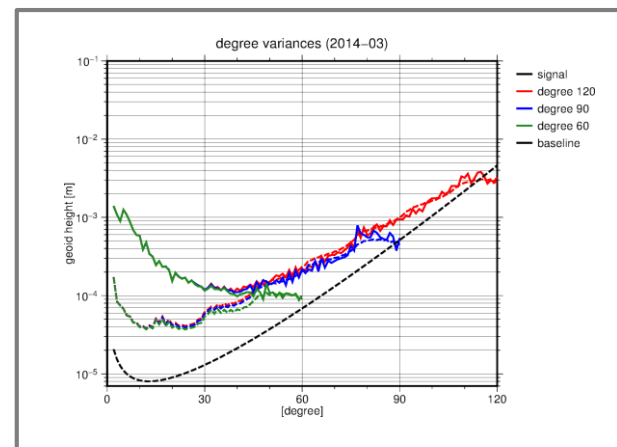
- GRACE Level-1B data from 2002-04 to 2016-03
- ITSG orbit product (Zehentner et al. 2015)
- Improved satellite attitude (Klinger et al. 2014)

## Unconstrained monthly solutions:

- Degree 60, 90, 120
- Full normal equations in SINEX format are published

## Daily Kalman smoothed solutions:

- Degree 40



# ITSG-Grace2016

## Background models:

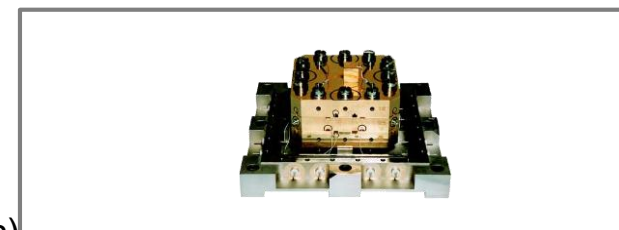
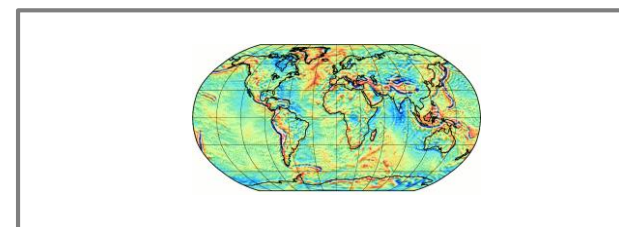
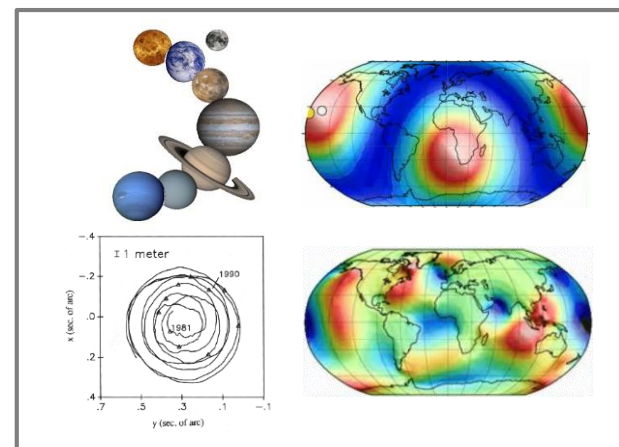
- Third body forces: JPL DE421
- Solid earth tides: IERS 2010
- Pole tides: IERS 2010
- Ocean tides: EOT11a
- Ocean pole tides: Desai 2004
- Atmospheric tides: Van Dam & Ray 2010
- Dealiasing: AOD1B RL05
- Relativistic effects: IERS 2010

## Restored models:

- Static field: GOCO05s
- Trend, Annual: GOCO05s

## Non-gravity parameters:

- Once per day: satellite state vector
- Once per day: accelerometer bias per axis (basis splines)
- Once per day: accelerometer scale factors



# Processing details

# Improvements since ITSG-Grace2014

**Multiple improvements within the processing chain:**

# Improvements since ITSG-Grace2014

## Multiple improvements within the processing chain:

- 1) Updated background models

# Improvements since ITSG-Grace2014

## Multiple improvements within the processing chain:

- 1) Updated background models
- 2) Instrument data screening



# Improvements since ITSG-Grace2014

## Multiple improvements within the processing chain:

- 1) Updated background models
- 2) Instrument data screening
- 3) Improved accelerometer calibration

# Improvements since ITSG-Grace2014

## Multiple improvements within the processing chain:

- 1) Updated background models
- 2) Instrument data screening
- 3) Improved accelerometer calibration
- 4) Improved numerical orbit integration

# Improvements since ITSG-Grace2014

## Multiple improvements within the processing chain:

- 1) Updated background models
- 2) Instrument data screening
- 3) Improved accelerometer calibration
- 4) Improved numerical orbit integration
- 5) Improved covariance function estimation

# Improvements since ITSG-Grace2014

## Multiple improvements within the processing chain:

- 1) Updated background models
- 2) Instrument data screening
- 3) Improved accelerometer calibration
- 4) Improved numerical orbit integration
- 5) Improved covariance function estimation
- 6) Co-estimation of constrained daily variations:  
constraints based on improved error estimates for the dealiasing models

# Accelerometer calibration

## Accelerometer bias & scale factors:

- Two-step approach: a-priori calibration for data screening
- Calibration equation:  $\mathbf{a}_{\text{true}} = \mathbf{S} \mathbf{a}_{\text{obs}} + \mathbf{b}$

# Accelerometer calibration

## Accelerometer bias & scale factors:

- Two-step approach: a-priori calibration for data screening
- Calibration equation:  $\mathbf{a}_{\text{true}} = \mathbf{S} \mathbf{a}_{\text{obs}} + \mathbf{b}$

## (1) Bias:

- Estimation: once per day
- Parameterization: uniform cubic basis splines (UCBS), with a 6h knot interval

# Accelerometer calibration

## Accelerometer bias & scale factors:

- Two-step approach: a-priori calibration for data screening
- Calibration equation:  $\mathbf{a}_{\text{true}} = \mathbf{S} \mathbf{a}_{\text{obs}} + \mathbf{b}$

$$\text{with } \mathbf{S} = \begin{bmatrix} s_x & \alpha + \zeta & \beta - \epsilon \\ \alpha - \zeta & s_y & \gamma + \delta \\ \beta + \epsilon & \gamma - \delta & s_z \end{bmatrix}$$

### (1) Bias:

- Estimation: once per day
- Parameterization: uniform cubic basis splines (UCBS), with a 6h knot interval

### (2) Scale factors:

- Estimation: once per day
- Parameterization: fully-populated scale factor matrix
- Off-diagonal elements: non-orthogonality of accelerometer axes (cross-talk), misalignment between SRF and AF

# Accelerometer calibration

## Accelerometer bias & scale factors:

- Two-step approach: a-priori calibration for data screening

- Calibration equation:  $\mathbf{a}_{\text{true}} = \mathbf{S} \mathbf{a}_{\text{obs}} + \mathbf{b}$

$$\text{with } \mathbf{S} = \begin{bmatrix} s_x & \alpha + \zeta & \beta - \epsilon \\ \alpha - \zeta & s_y & \gamma + \delta \\ \beta + \epsilon & \gamma - \delta & s_z \end{bmatrix}$$

- Scale parameters

### (1) Bias:

- Estimation: once per day
- Parameterization: uniform cubic basis splines (UCBS), with a 6h knot interval

### (2) Scale factors:

- Estimation: once per day
- Parameterization: fully-populated scale factor matrix
- Off-diagonal elements: non-orthogonality of accelerometer axes (cross-talk), misalignment between SRF and AF



# Accelerometer calibration

## Accelerometer bias & scale factors:

- Two-step approach: a-priori calibration for data screening

- Calibration equation:  $\mathbf{a}_{\text{true}} = \mathbf{S} \mathbf{a}_{\text{obs}} + \mathbf{b}$

$$\text{with } \mathbf{S} = \begin{bmatrix} s_x & \alpha + \zeta & \beta - \epsilon \\ \alpha - \zeta & s_y & \gamma + \delta \\ \beta + \epsilon & \gamma - \delta & s_z \end{bmatrix}$$

- **Scale parameters**
- **Shear parameters**

### (1) Bias:

- Estimation: once per day
- Parameterization: uniform cubic basis splines (UCBS), with a 6h knot interval

### (2) Scale factors:

- Estimation: once per day
- Parameterization: fully-populated scale factor matrix
- Off-diagonal elements: non-orthogonality of accelerometer axes (cross-talk), misalignment between SRF and AF

# Accelerometer calibration

## Accelerometer bias & scale factors:

- Two-step approach: a-priori calibration for data screening

- Calibration equation:  $\mathbf{a}_{\text{true}} = \mathbf{S} \mathbf{a}_{\text{obs}} + \mathbf{b}$

with  $\mathbf{S} = \begin{bmatrix} s_x & \alpha + \zeta & \beta - \epsilon \\ \alpha - \zeta & s_y & \gamma + \delta \\ \beta + \epsilon & \gamma - \delta & s_z \end{bmatrix}$

- Scale parameters
- Shear parameters
- Rotation parameters

### (1) Bias:

- Estimation: once per day
- Parameterization: uniform cubic basis splines (UCBS), with a 6h knot interval

### (2) Scale factors:

- Estimation: once per day
- Parameterization: fully-populated scale factor matrix
- Off-diagonal elements: non-orthogonality of accelerometer axes (cross-talk), misalignment between SRF and AF

# Accelerometer calibration

## Accelerometer bias & scale factors:

- Two-step approach: a-priori calibration for data screening
- Calibration equation:  $\mathbf{a}_{\text{true}} = \mathbf{S} \mathbf{a}_{\text{obs}} + \mathbf{b}$

$$\mathbf{S} = \begin{bmatrix} s_x & \alpha + \zeta & \beta - \epsilon \\ \alpha - \zeta & s_y & \gamma + \delta \\ \gamma - \delta & & s_z \end{bmatrix}$$

- Scale parameters
- Shear parameters
- Rotation parameters

### (1) Bias:

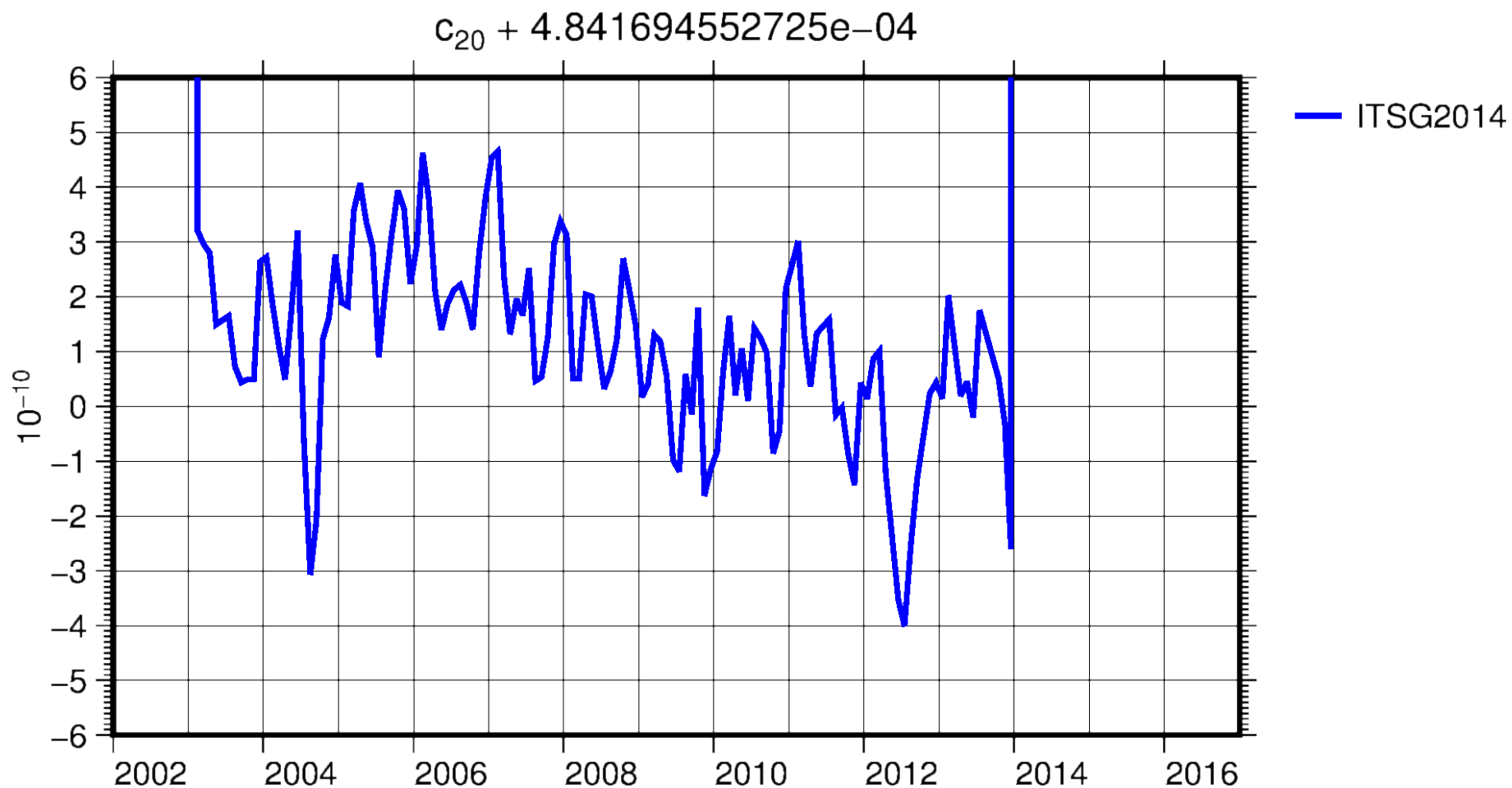
- Estimation: once per day
- Parameterization: uniform cubic basis spline, knot interval

### (2) Scale factors:

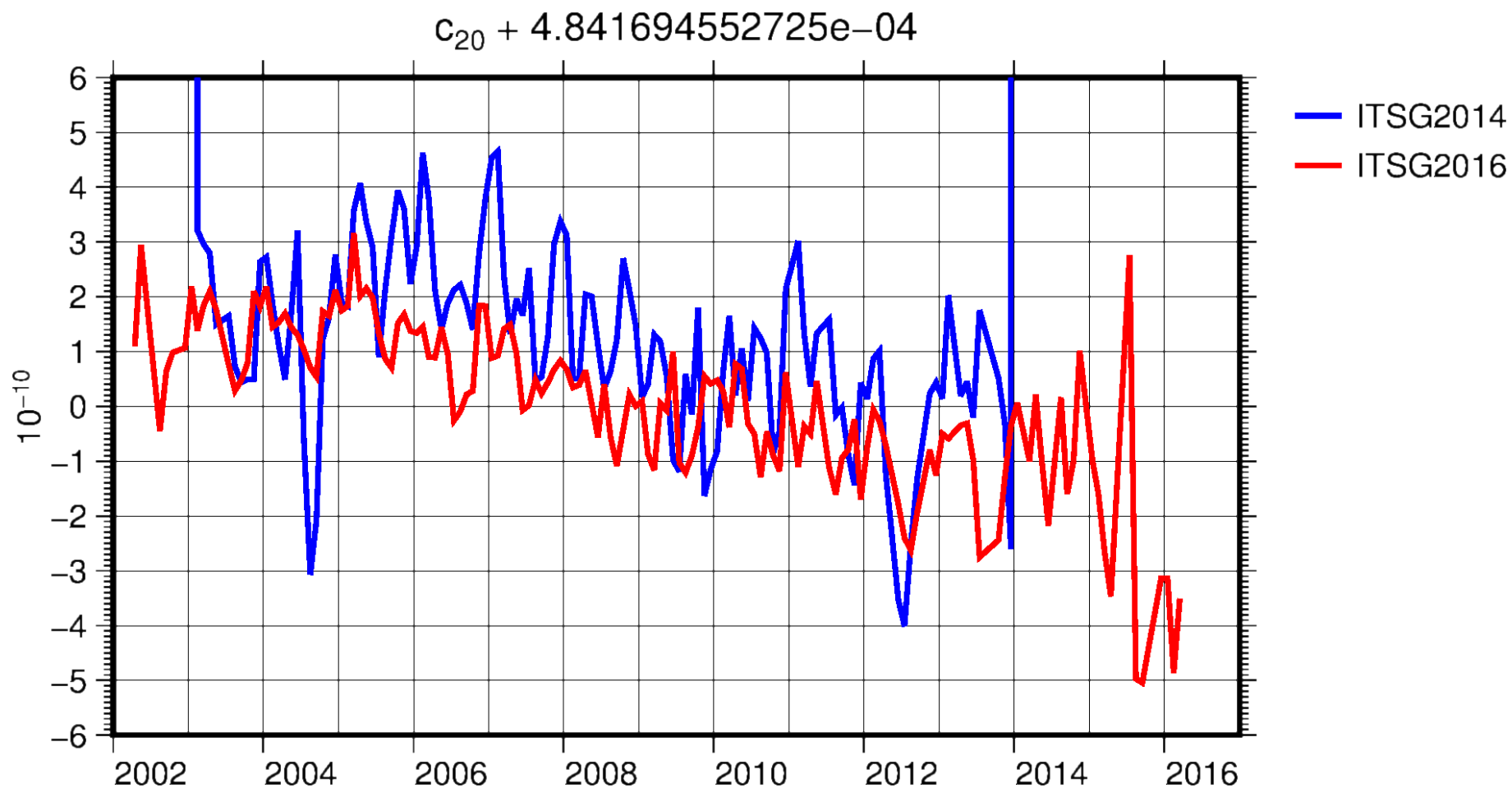
- Estimation: once per day
- Parameterization: fully-populated scale factor matrix
- Off-diagonal elements: non-orthogonality of accelerometer axes (cross-talk), misalignment between SRF and AF

**Paper submitted  
(Klinger et. al.)**

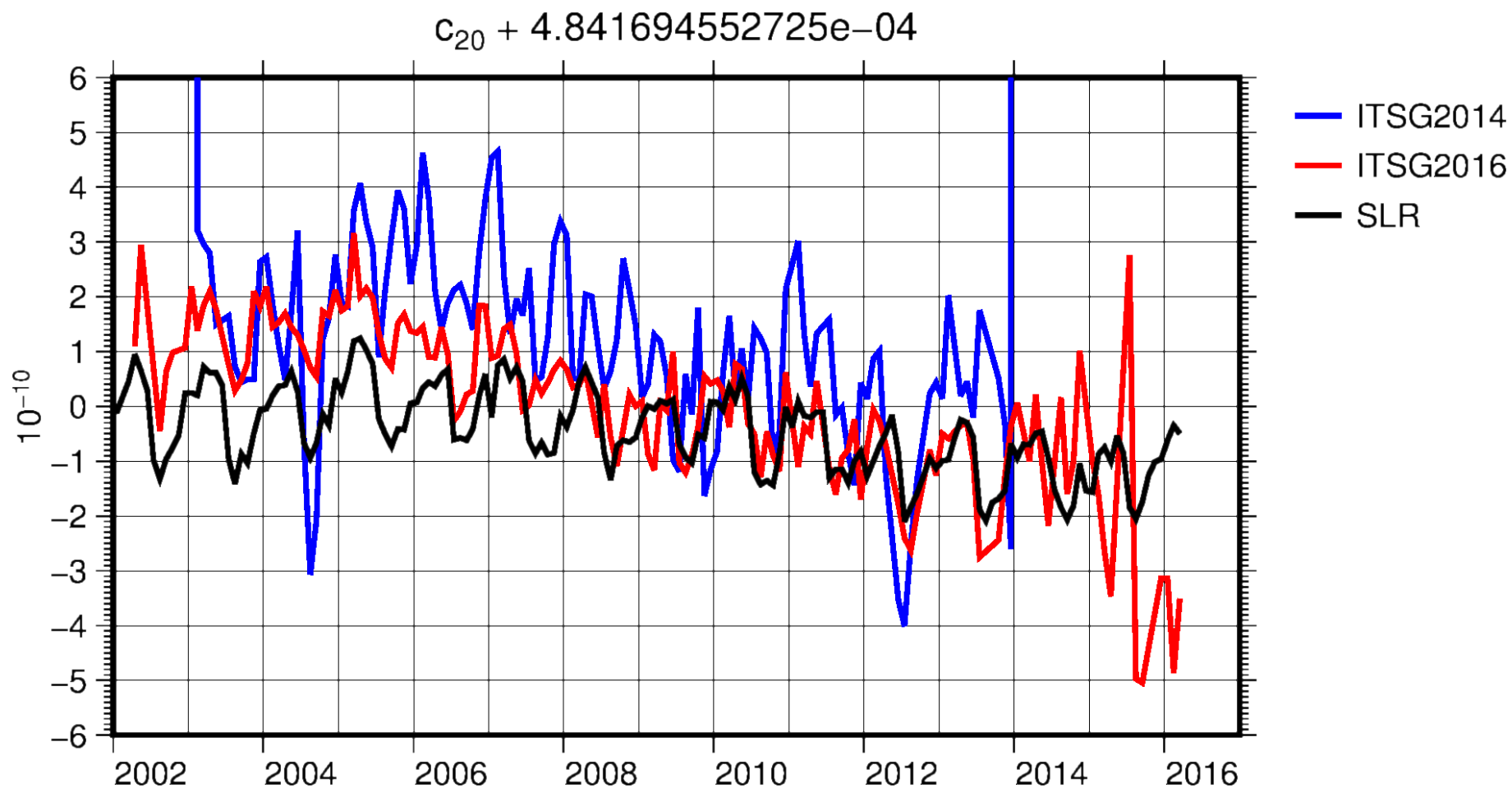
# Accelerometer calibration – Impact on C20



# Accelerometer calibration – Impact on C20

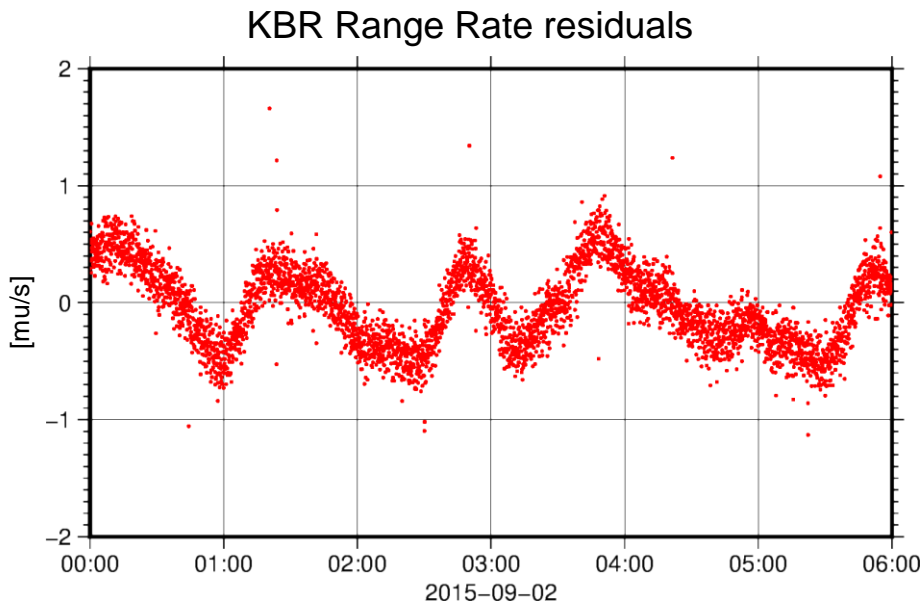


# Accelerometer calibration – Impact on C20



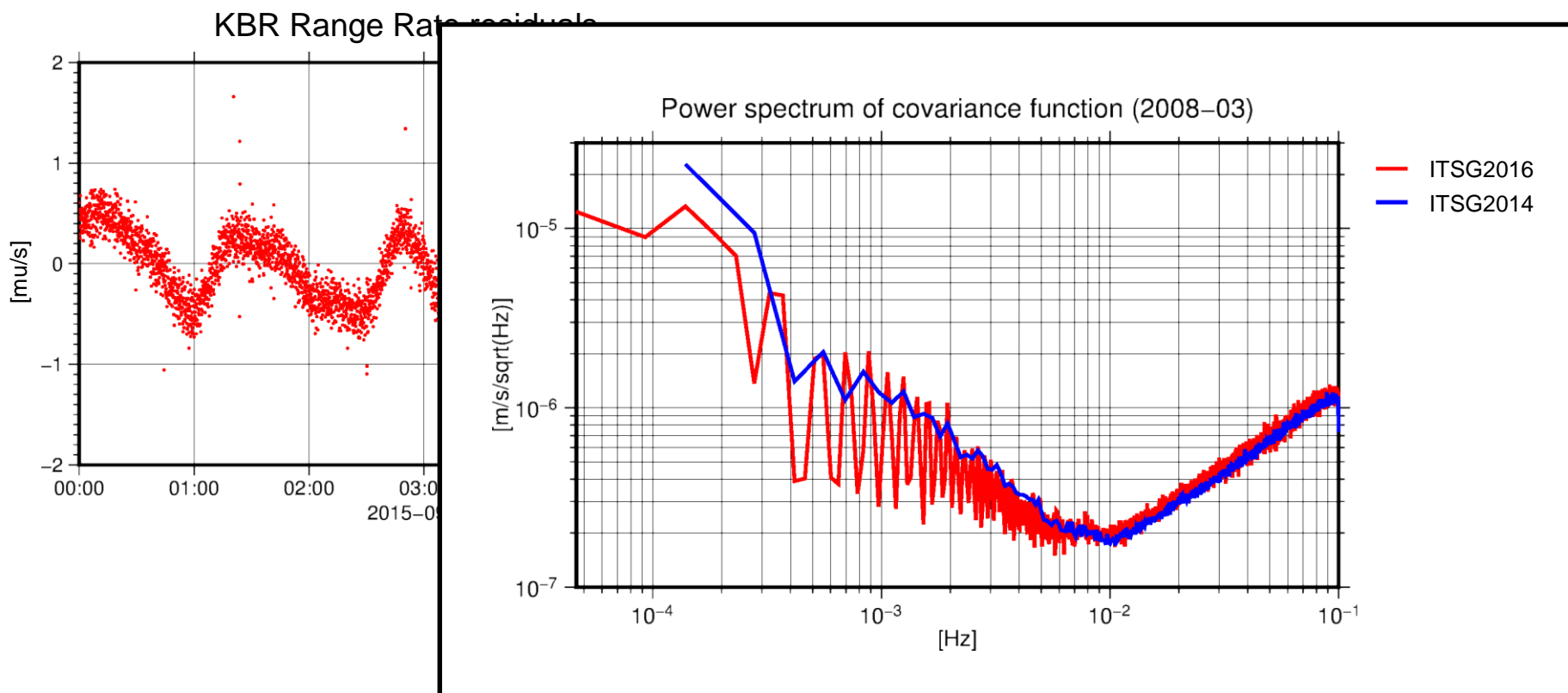
# Noise modeling – covariance function

- **Empirical covariance function:** decorrelation of KBR range-rate data
- **Robust covariance estimator:** guarantees outlier-resistant covariance estimation



# Noise modeling – covariance function

- **Empirical covariance function:** decorrelation of KBR range-rate data
- **Robust covariance estimator:** guarantees outlier-resistant covariance estimation

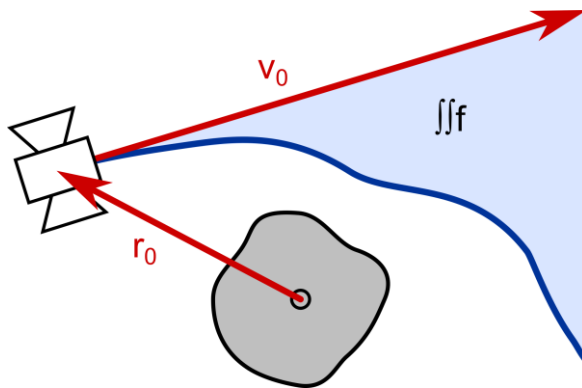




# Orbit integration

## Elliptical reference orbit replaces linear motions:

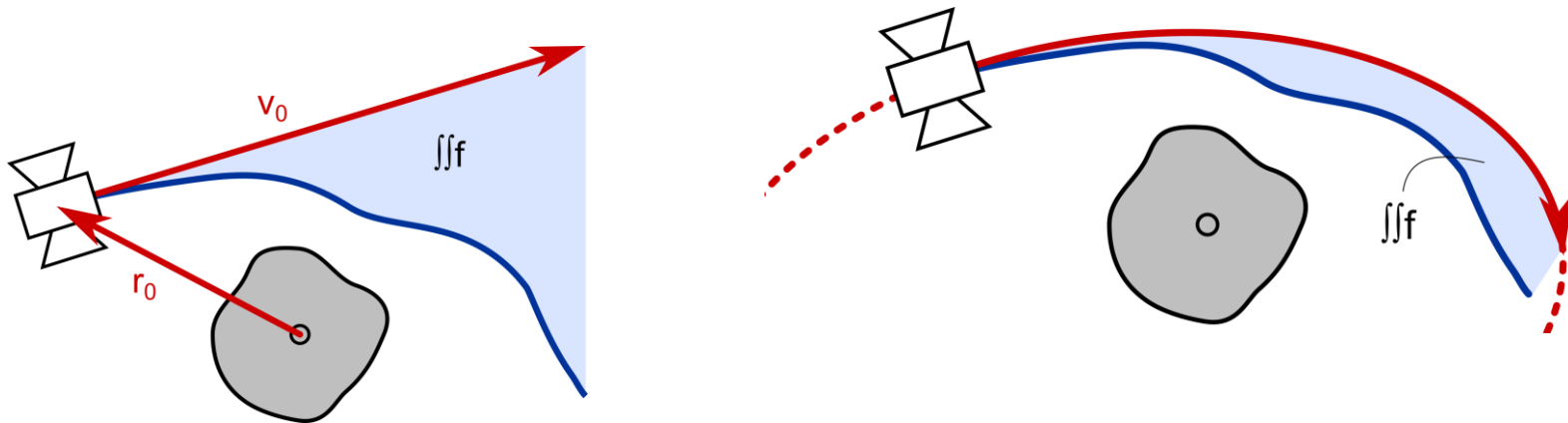
- Improved force model integration for dynamic orbit computation (Encke's method)
- Reduced processing artifacts in adjusted SST observations and residuals



# Orbit integration

## Elliptical reference orbit replaces linear motions:

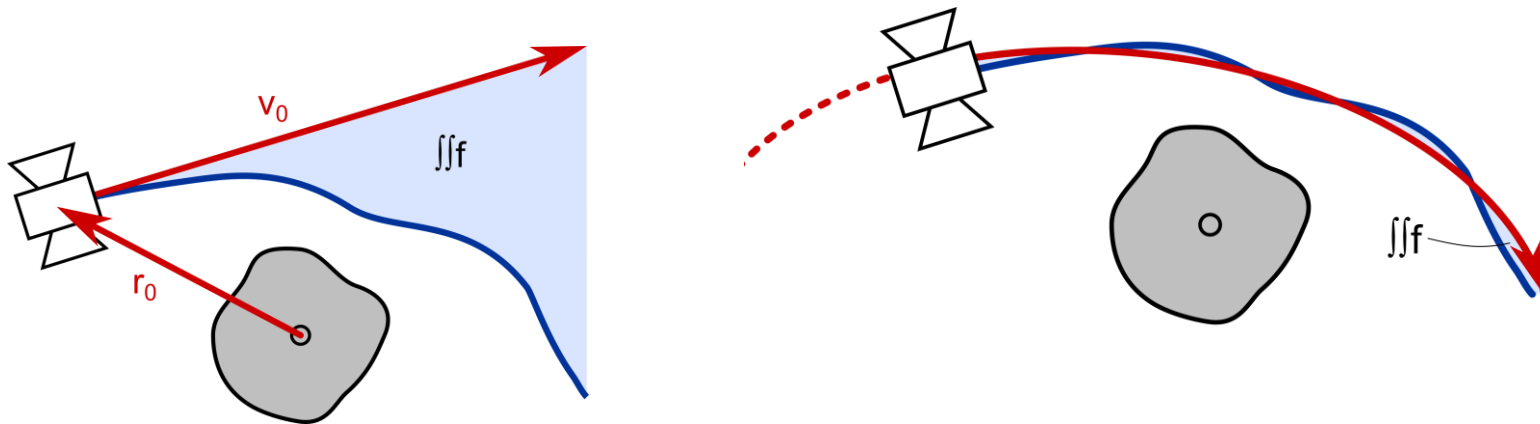
- Improved force model integration for dynamic orbit computation (Encke's method)
- Reduced processing artifacts in adjusted SST observations and residuals



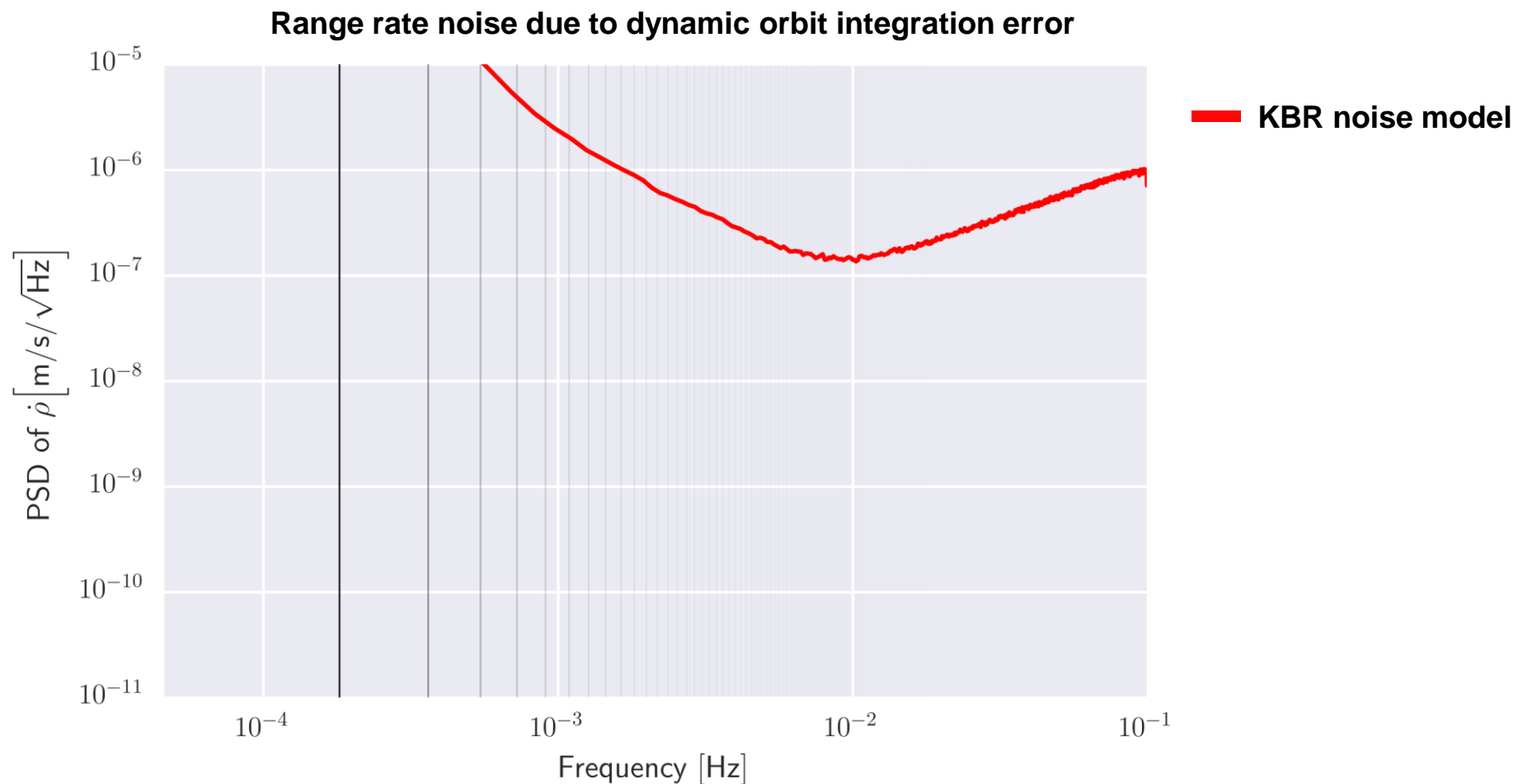
# Orbit integration

## Elliptical reference orbit replaces linear motions:

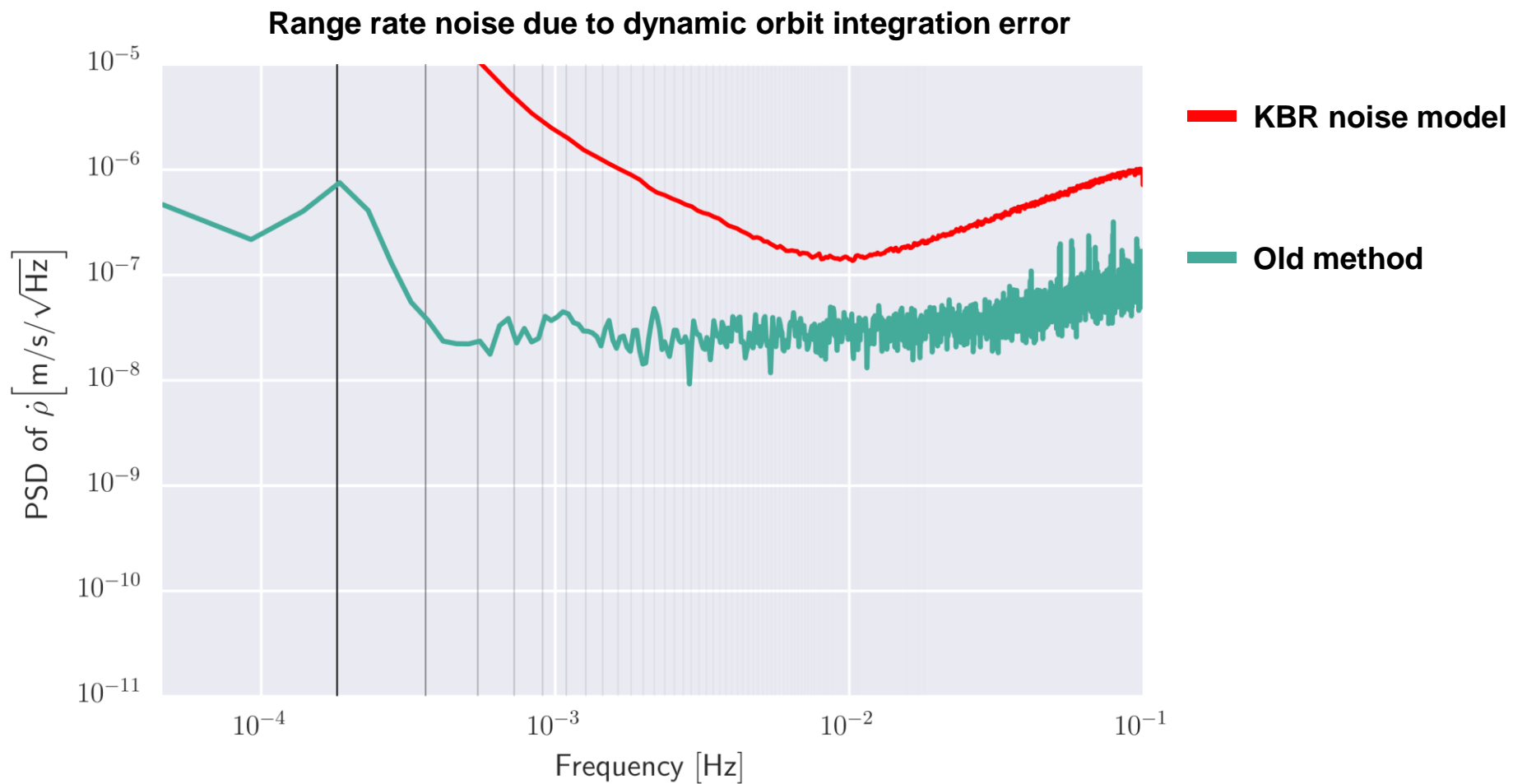
- Improved force model integration for dynamic orbit computation (Encke's method)
- Reduced processing artifacts in adjusted SST observations and residuals



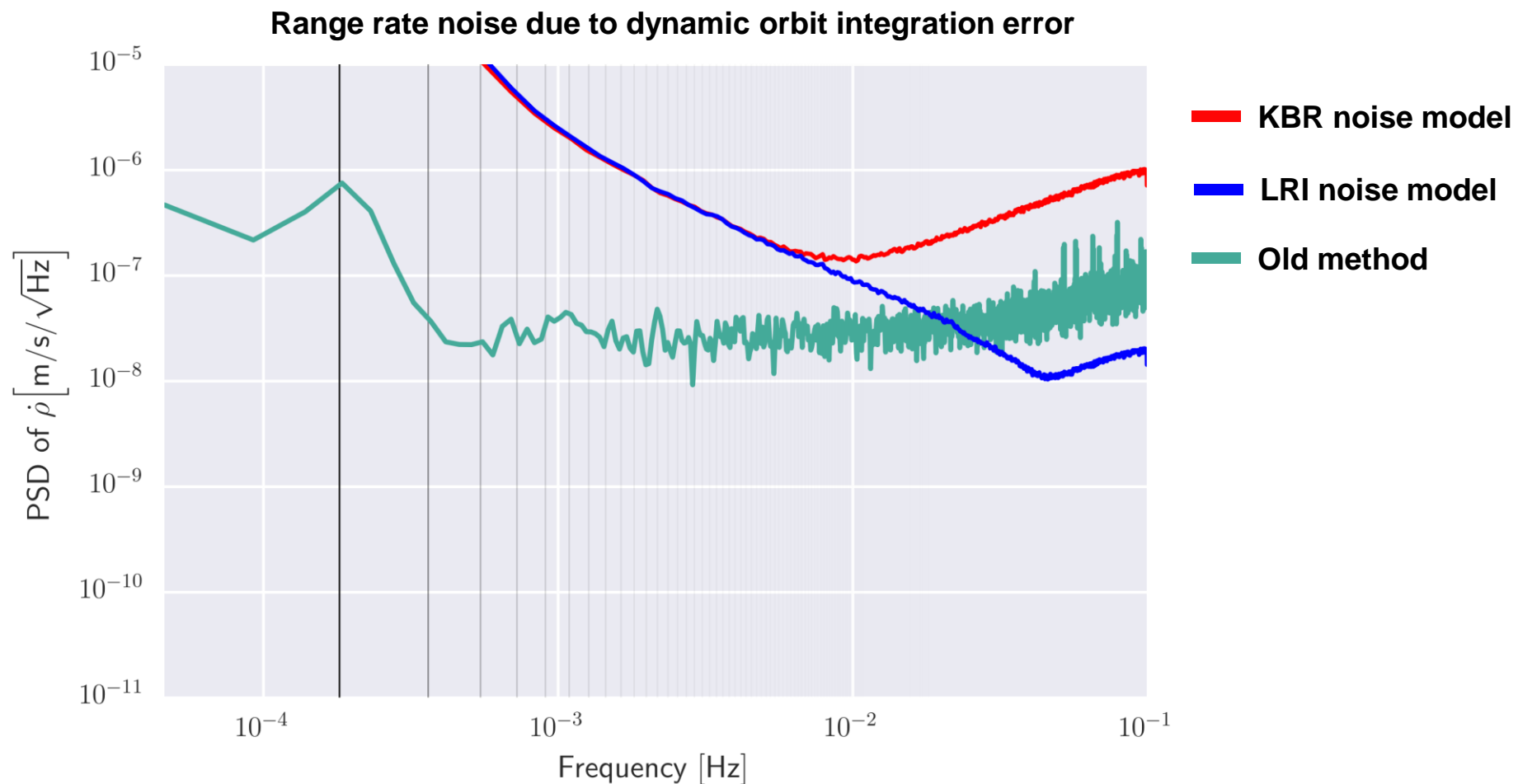
# Orbit integration



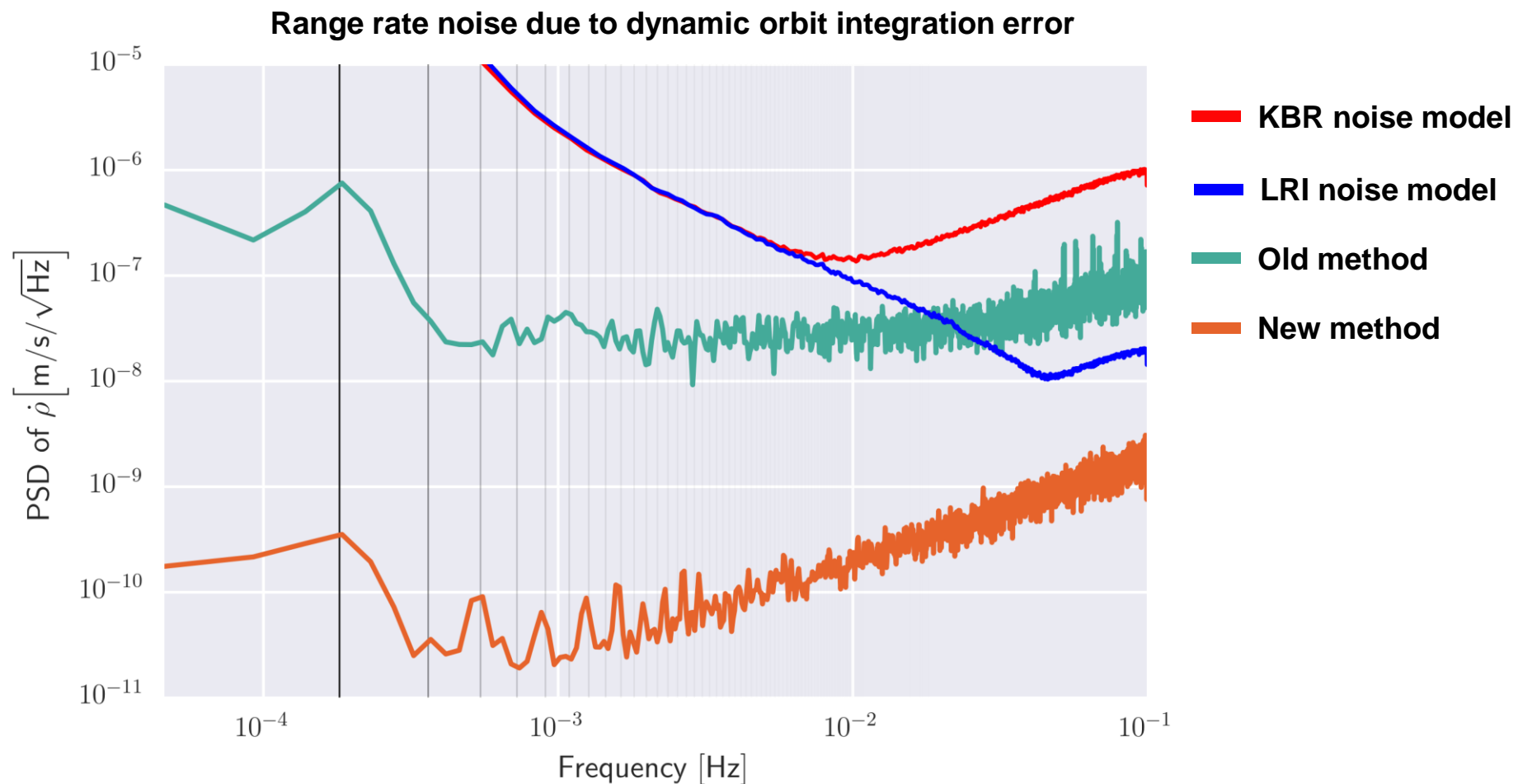
# Orbit integration



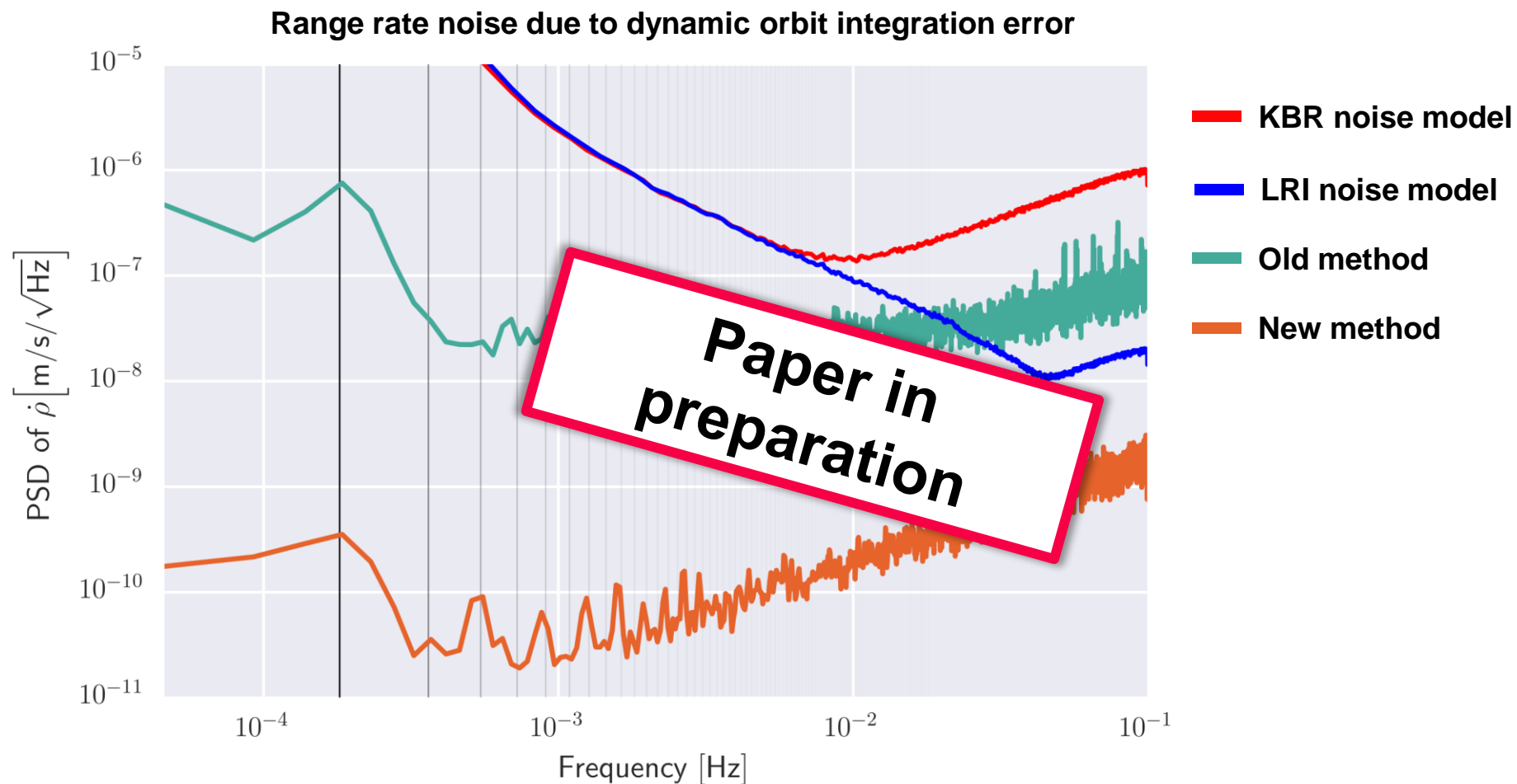
# Orbit integration



# Orbit integration



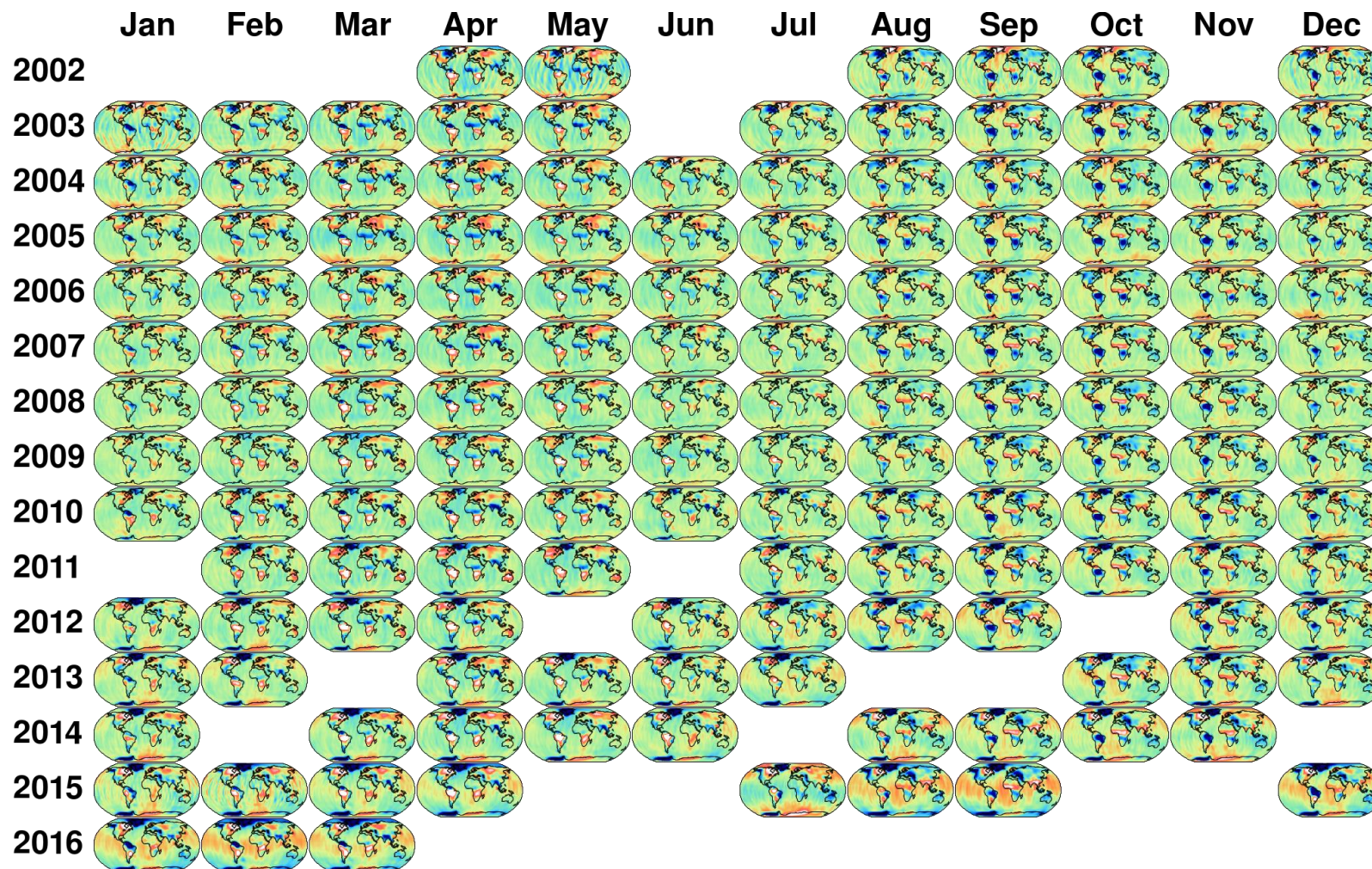
# Orbit integration





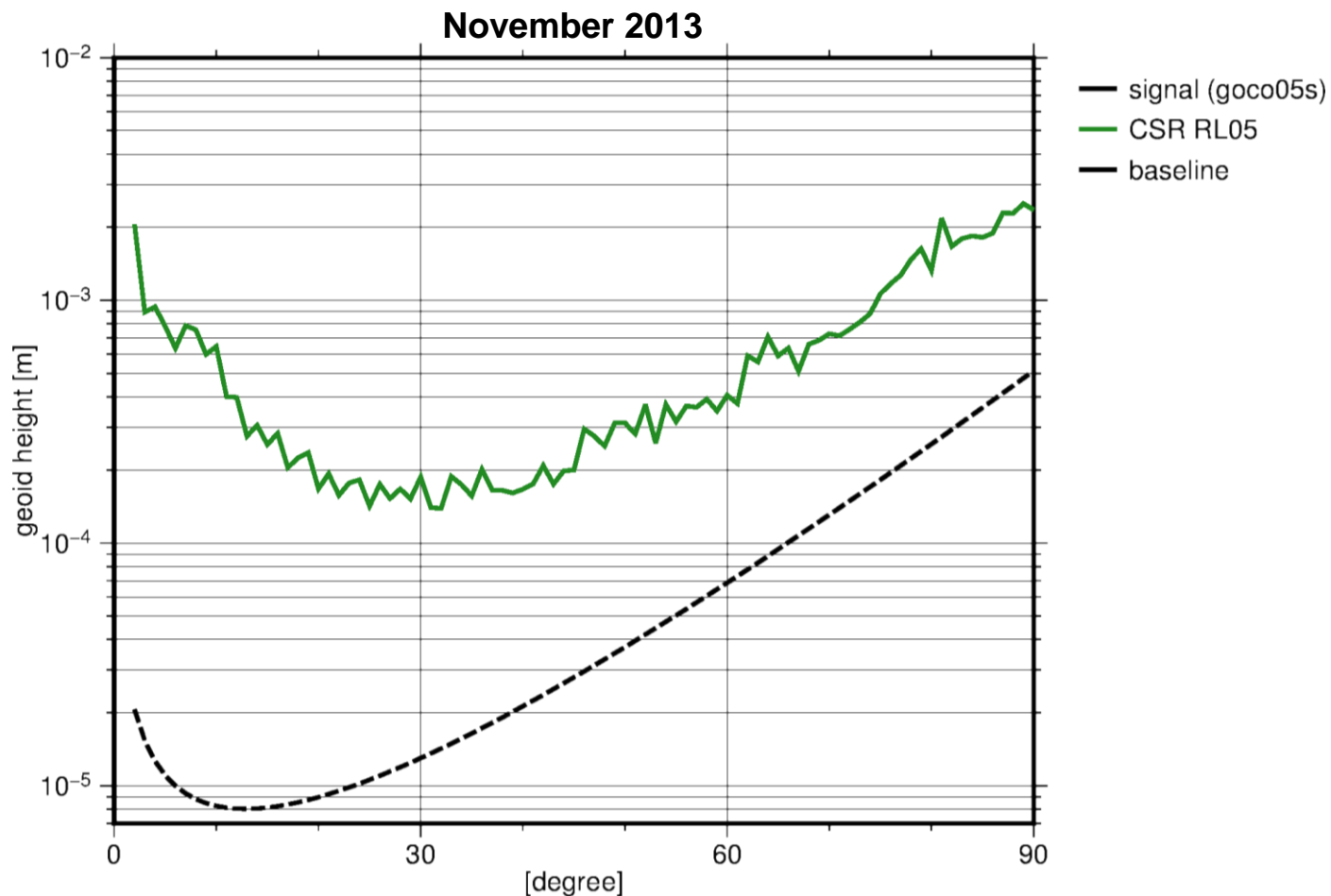
# Unconstrained monthly solutions

# ITSG-Grace2016 Monthly Solutions



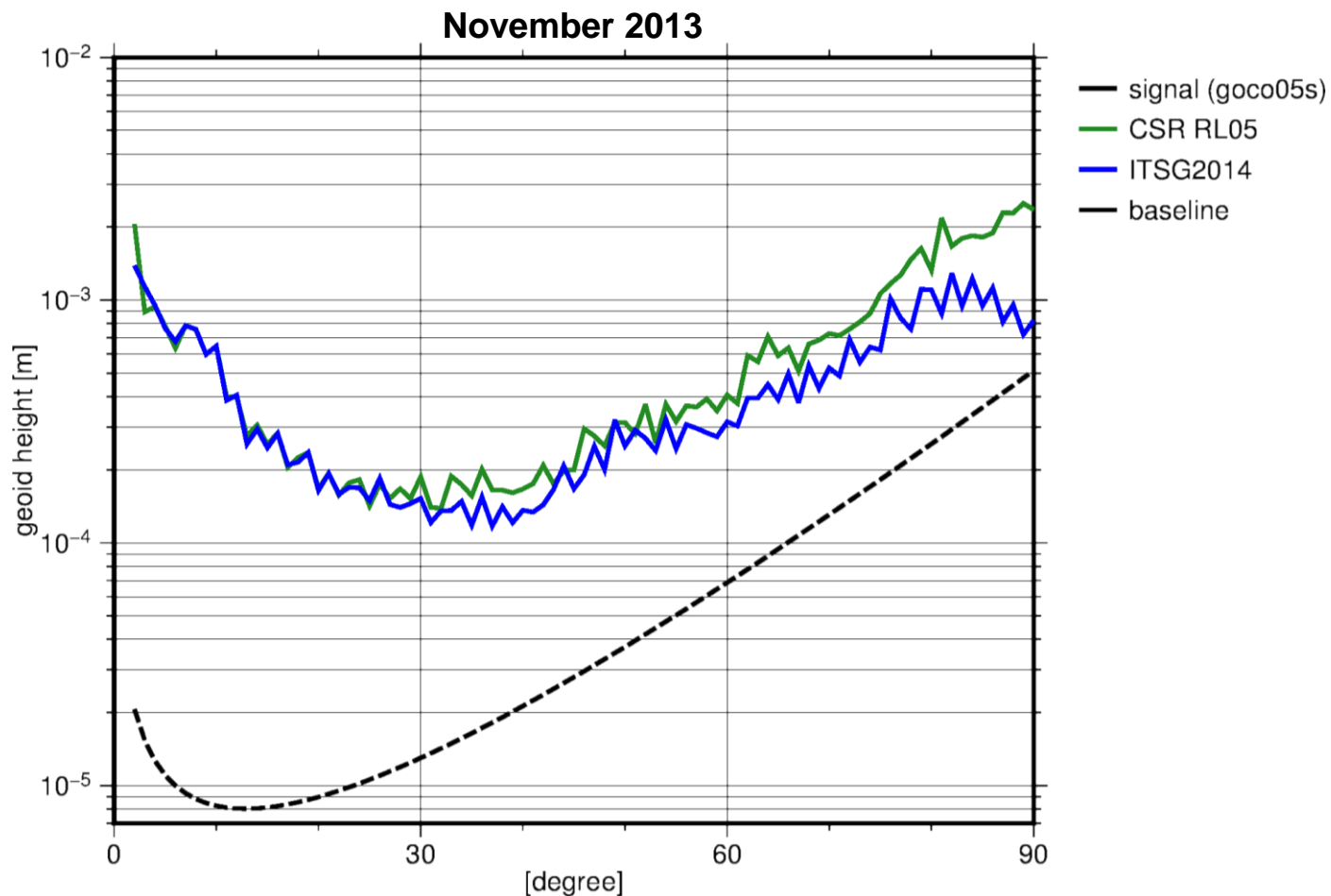
# ITSG-Grace2016 Monthly Solutions

Unconstrained monthly solutions: degree 90 comparison



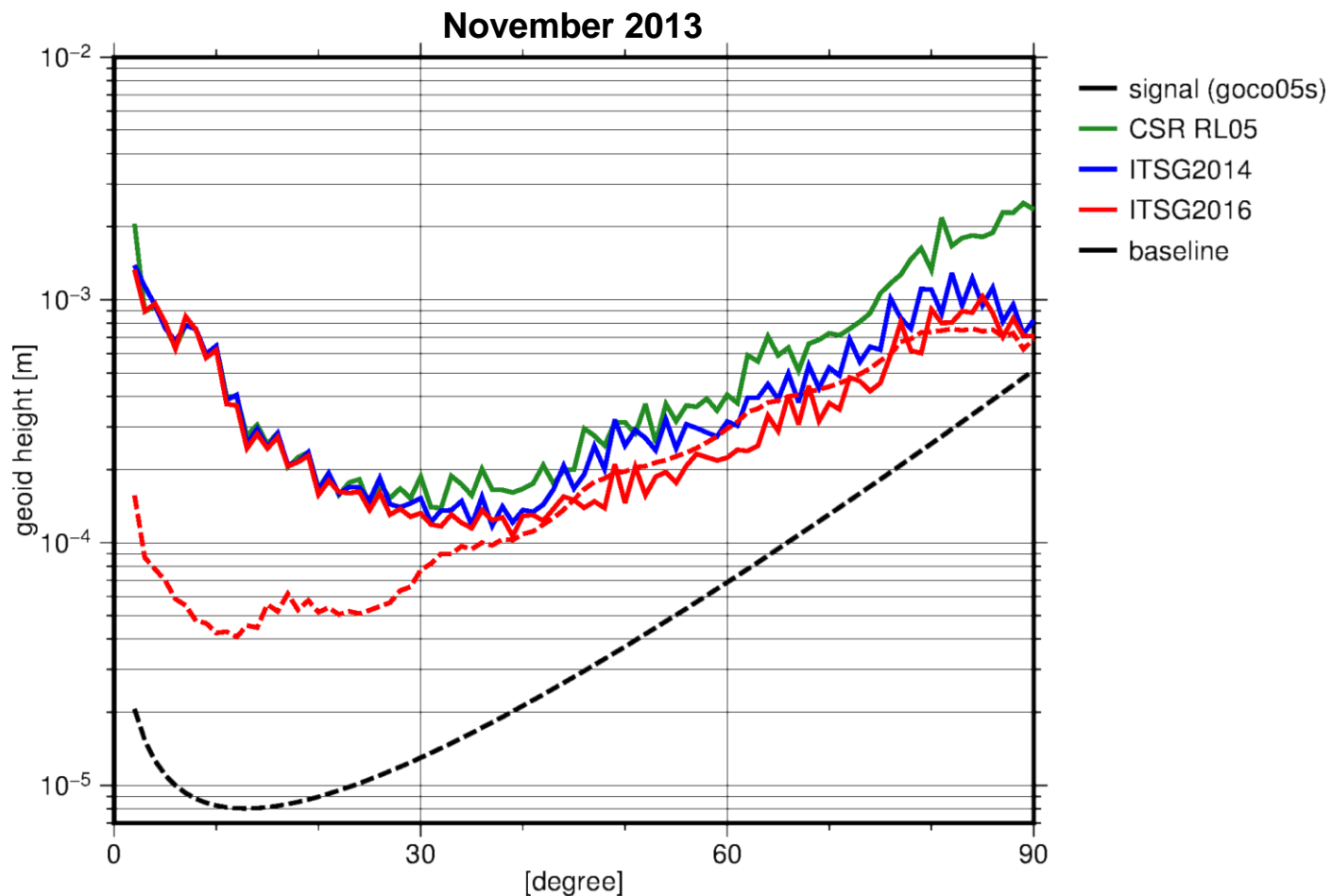
# ITSG-Grace2016 Monthly Solutions

Unconstrained monthly solutions: degree 90 comparison



# ITSG-Grace2016 Monthly Solutions

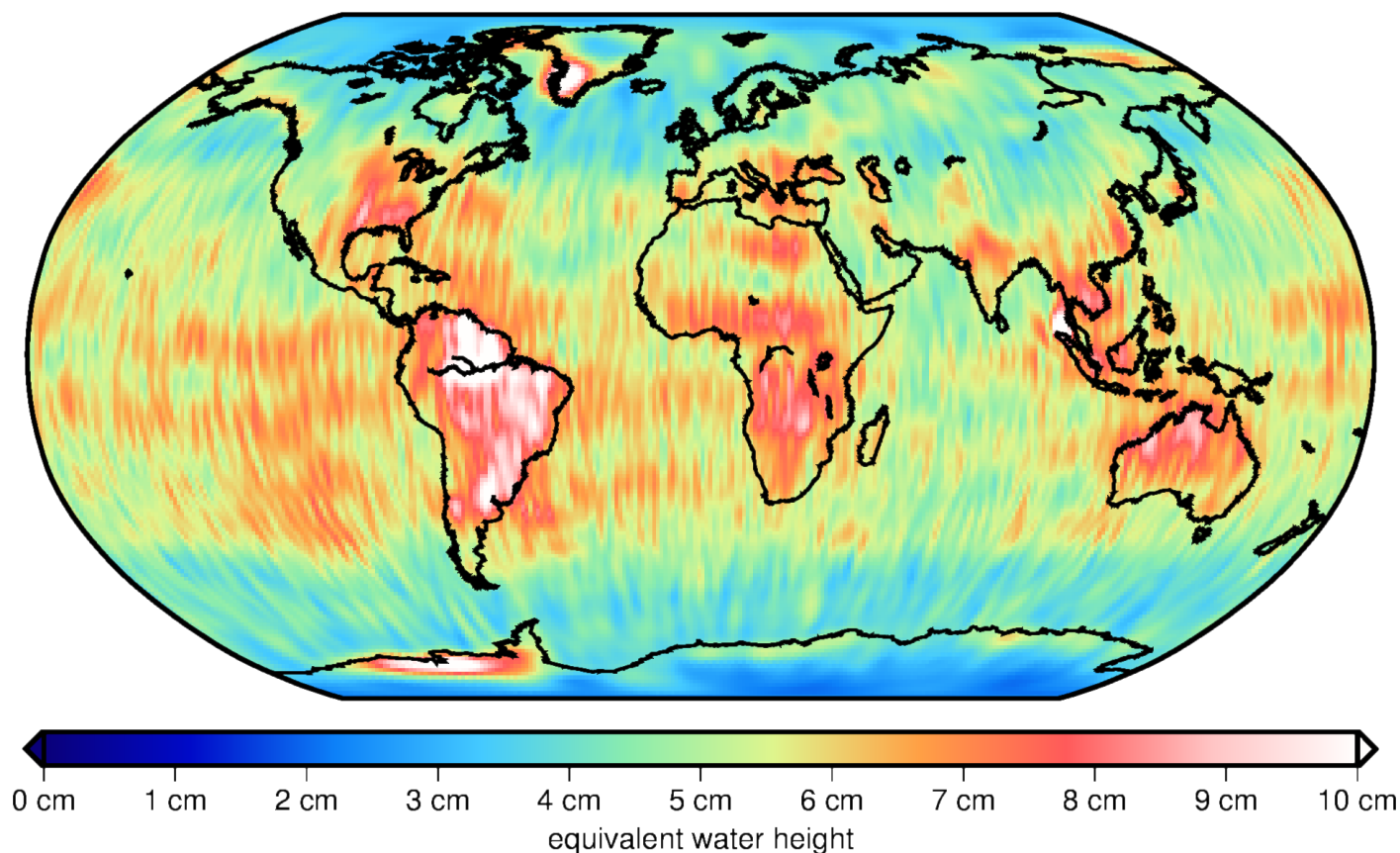
Unconstrained monthly solutions: degree 90 comparison



# Temporal RMS

CSR RL05 - trend/SA/SSA (Gauß 300km)

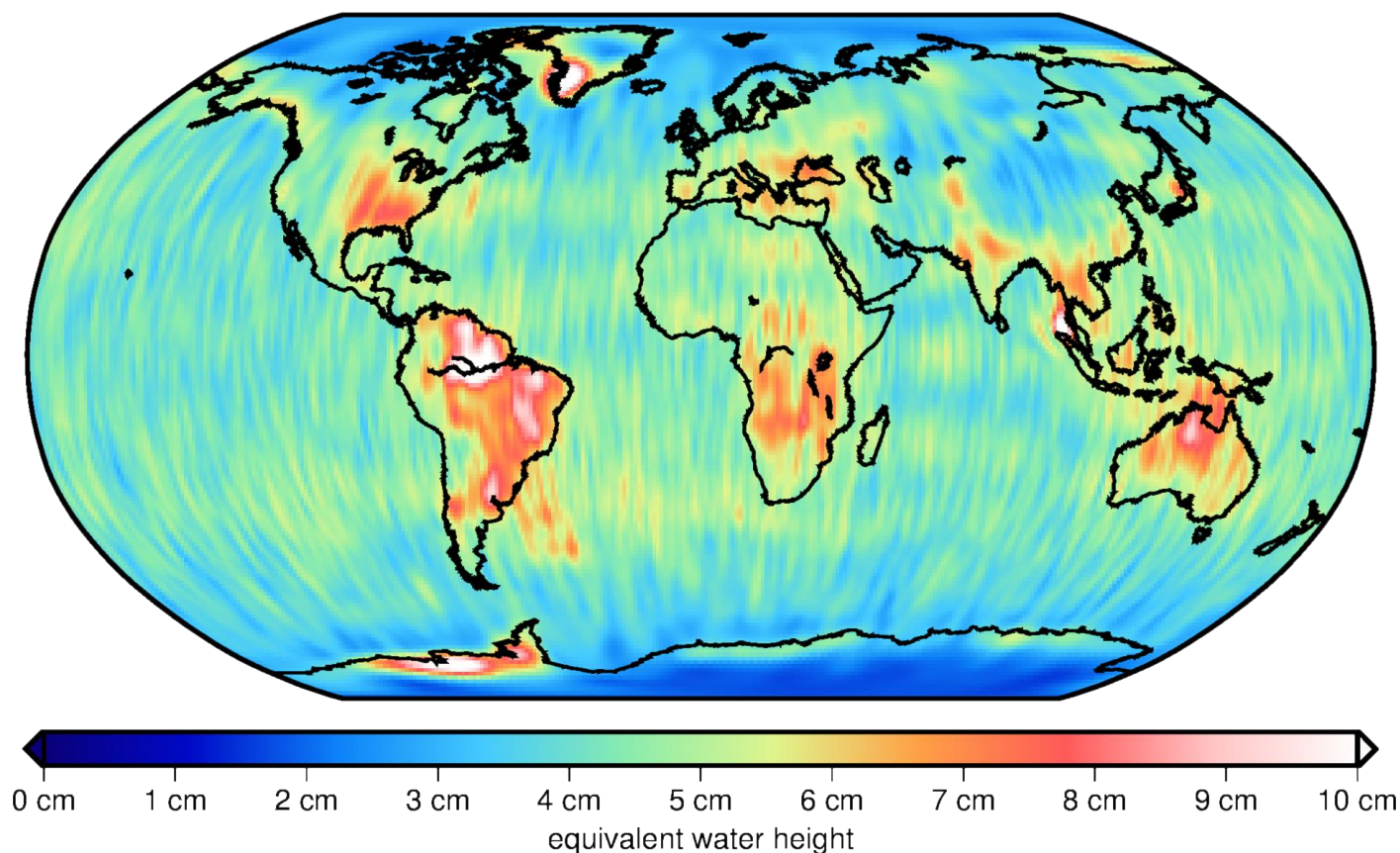
RMS = 5.5901



# Temporal RMS

ITSG-Grace2014 - trend/SA/SSA (Gauß 300km)

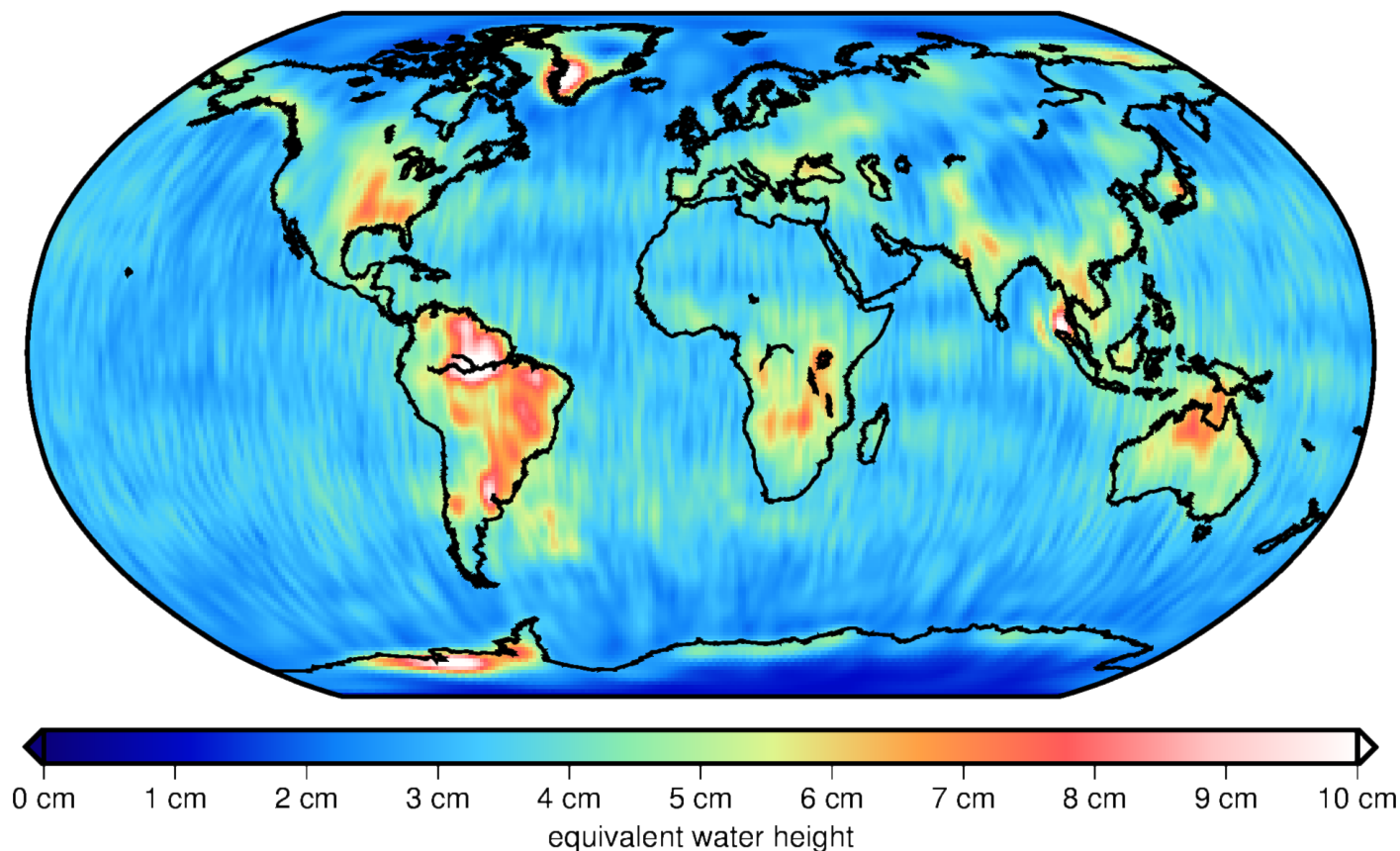
RMS = 4.6011



# Temporal RMS

ITSG-Grace2016 - trend/SA/SSA (Gauß 300km)

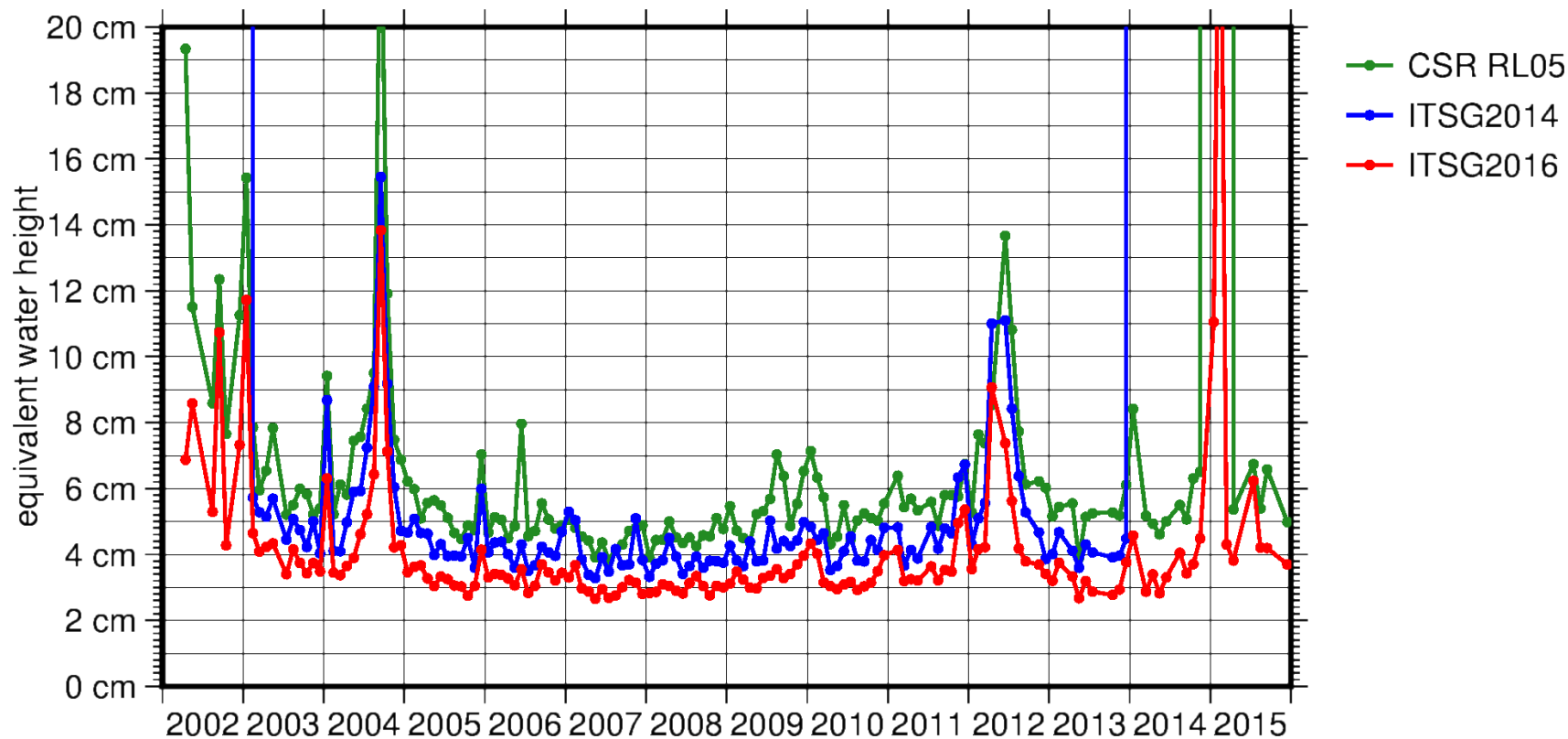
RMS = 3.7209





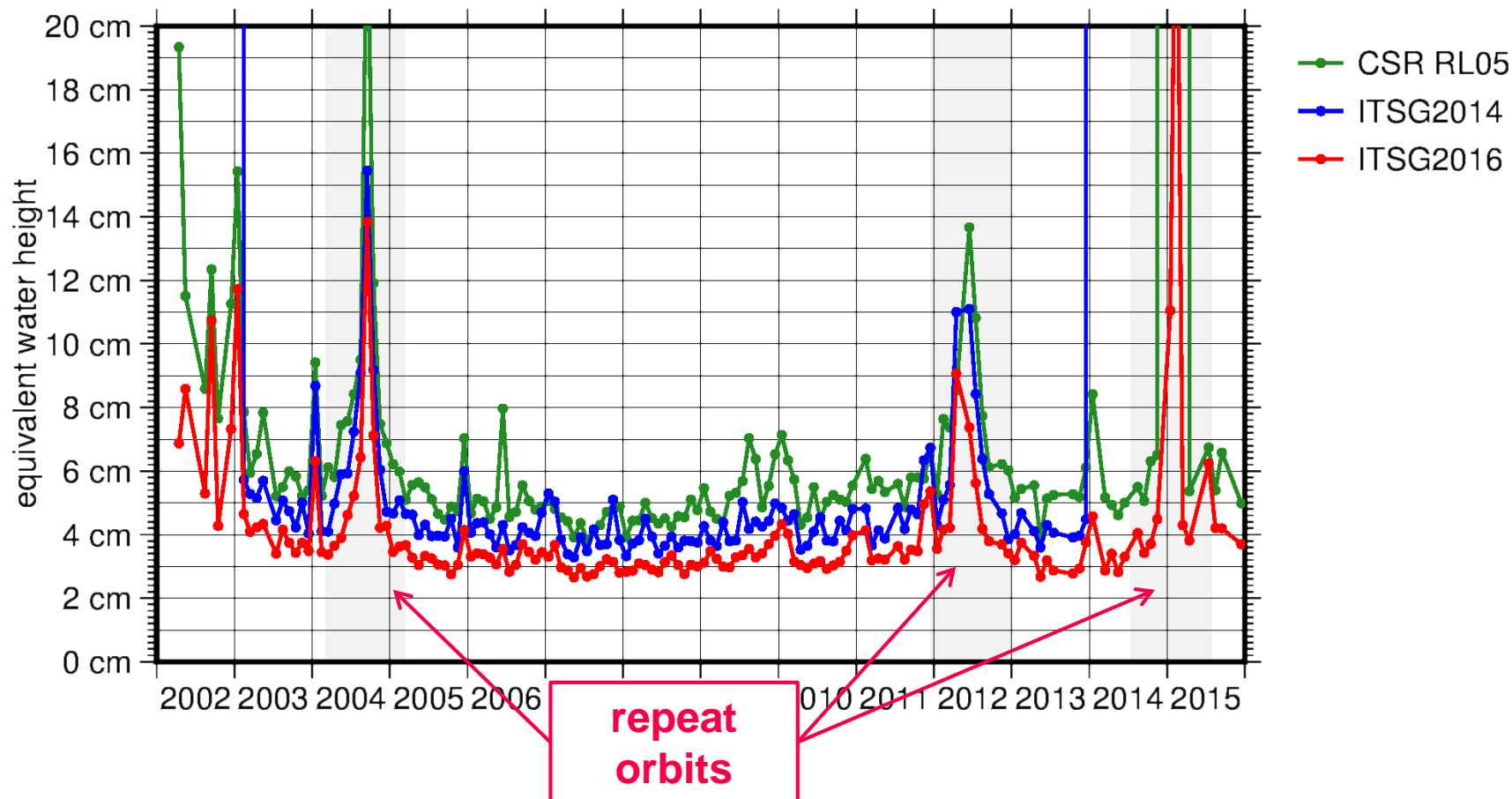
# Variability over the Oceans

Trend/Annual/Semiannual reduced (Gauß 300km)



# Variability over the Oceans

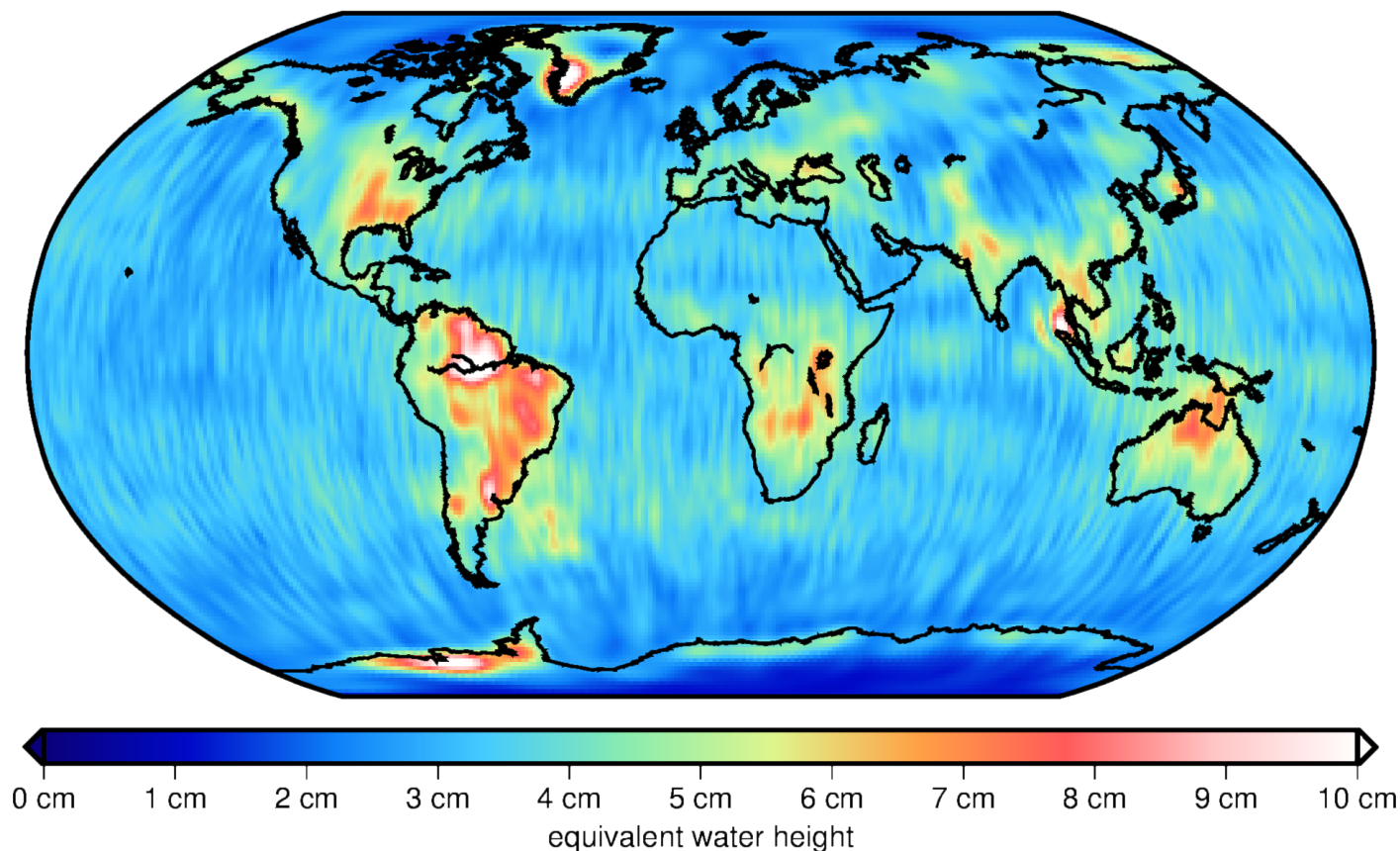
Trend/Annual/Semiannual reduced (Gauß 300km)



# Temporal RMS

ITSG-Grace2016 - trend/SA/SSA (Gauß 300km)

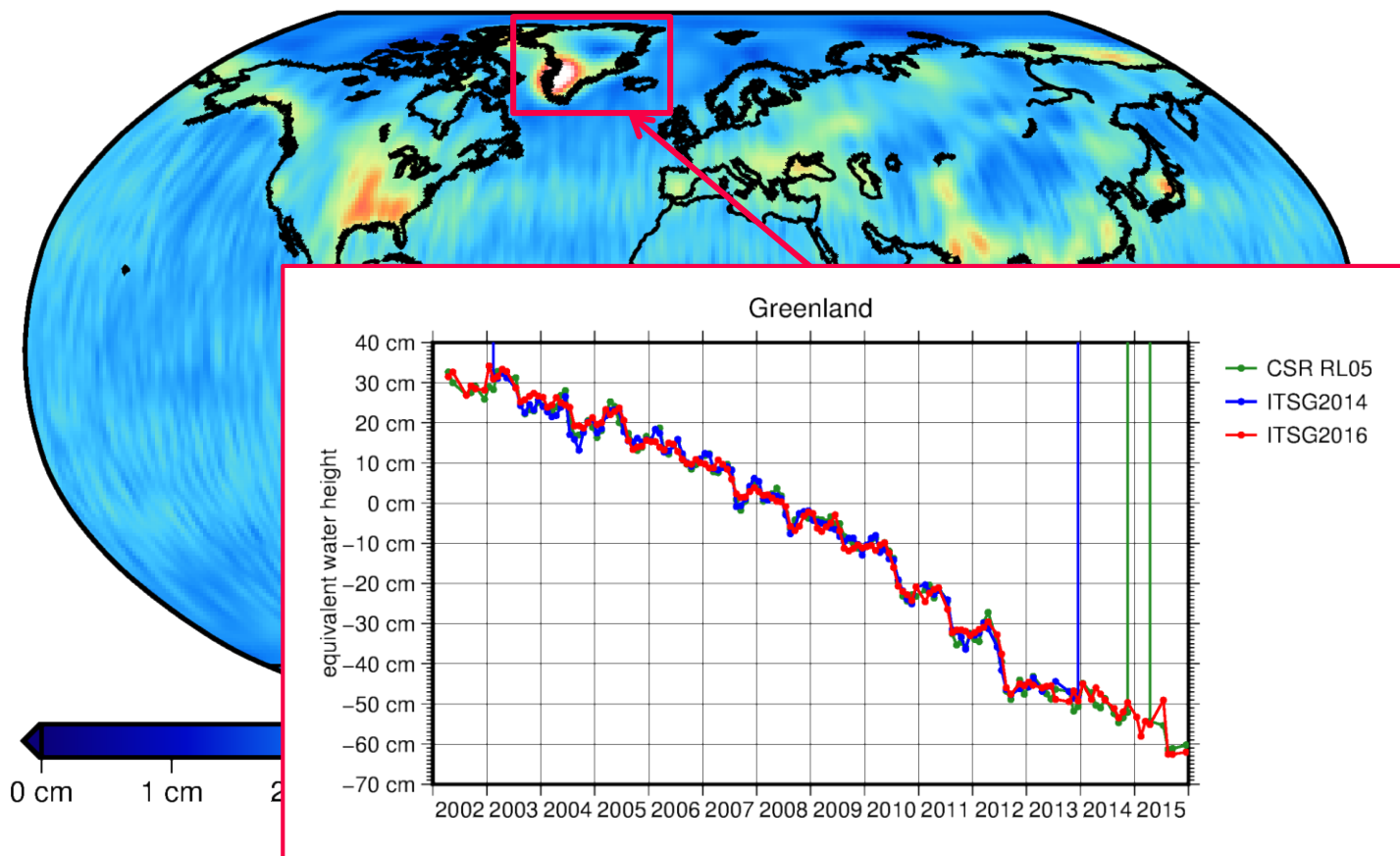
RMS = 3.7209



# Comparison of signals

ITSG-Grace2016 - trend/SA/SSA (Gauß 300km)

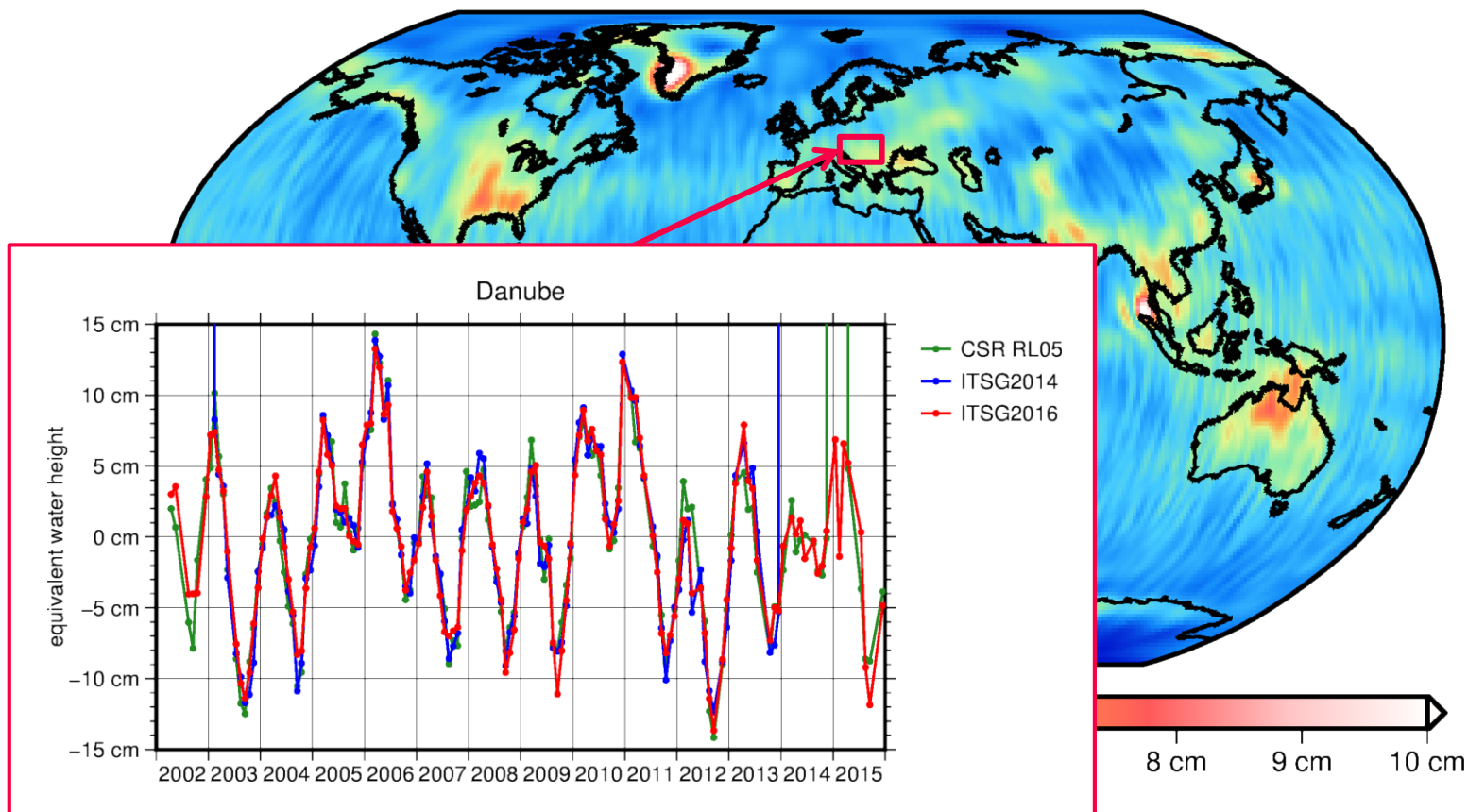
RMS = 3.7209



# Comparison of signals

ITSG-Grace2016 - trend/SA/SSA (Gauß 300km)

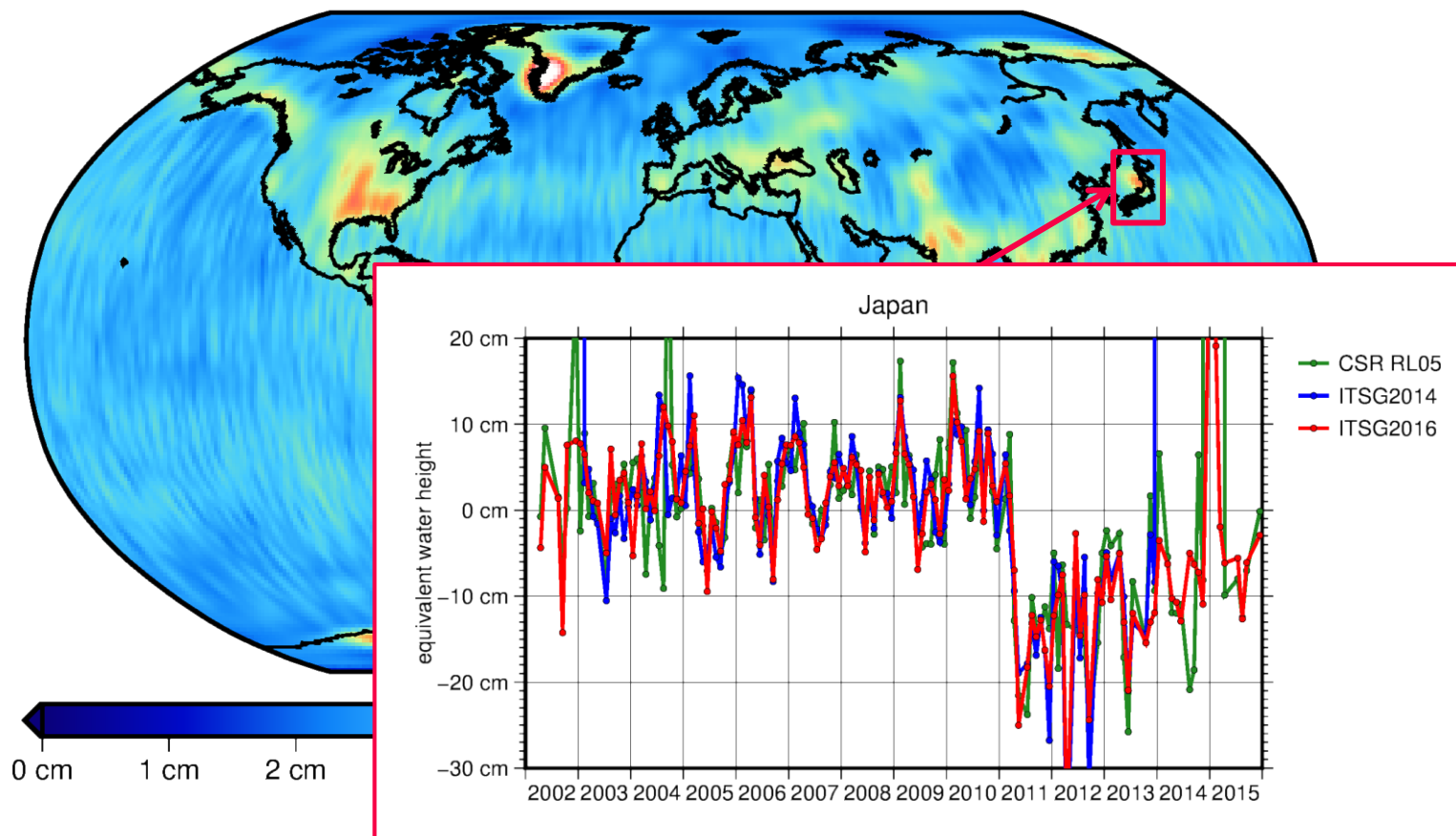
RMS = 3.7209



# Comparison of signals

ITSG-Grace2016 - trend/SA/SSA (Gauß 300km)

RMS = 3.7209



# Conclusions

## ITSG-Grace2014 vs. ITSG-Grace2016:

- Improved processing and updated models contribute to overall accuracy of monthly gravity field solutions
- Noise reduction w.r.t. ITSG-Grace2014 on the order of
  - 20% for  $n=15-25$
  - 40% for  $n=25-40$
  - 25% for  $n=40-90$
- Fully-populated scale factor matrix significantly improves C20 coefficient

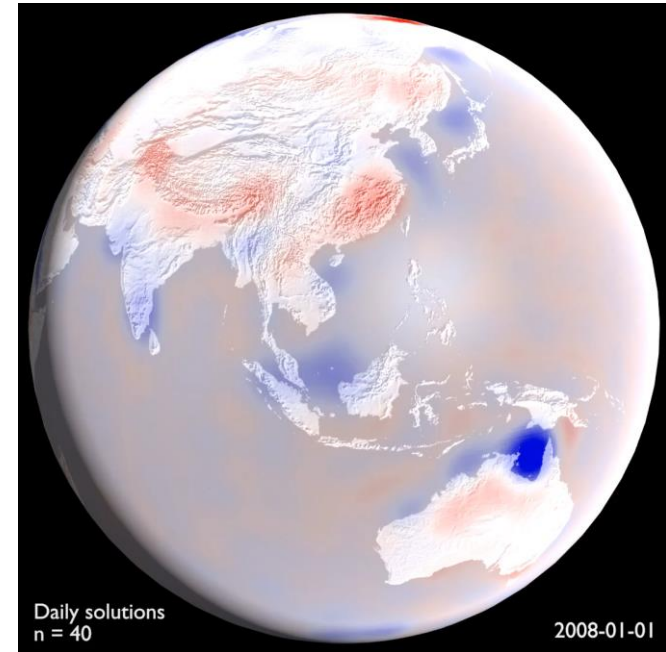
# ITSG-Grace2016

## Unconstrained monthly solutions:

- Degree 60, 90, 120
- Full normal equations in SINEX format are published

## Daily Kalman smoothed solutions:

- Degree 40





# ITSG-Grace2016

## Unconstrained monthly solutions:

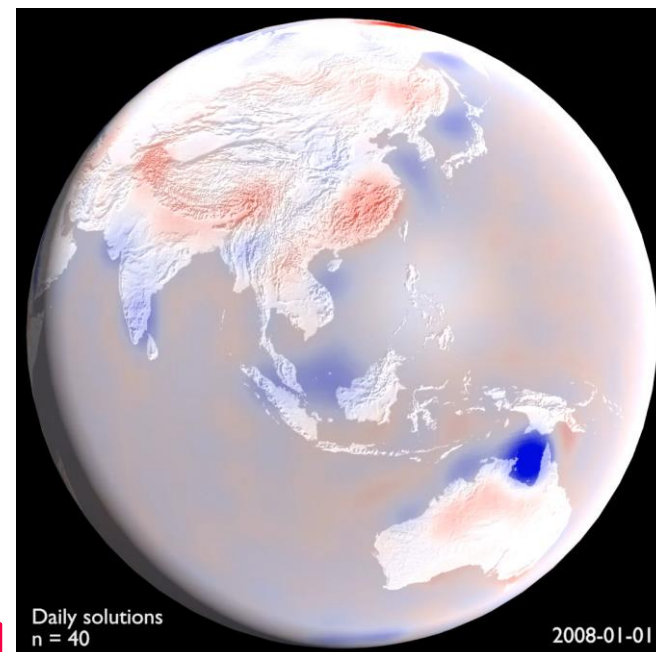
- Degree 60, 90, 120
- Full normal equations in SINEX format are published

## Daily Kalman smoothed solutions:

- Degree 40

**ITSG-Grace2016 Release available at:**

[ifg.tugraz.at/ITSG-Grace2016](http://ifg.tugraz.at/ITSG-Grace2016)



## Funding provided by:

- the *Austrian Research Promotion Agency*
- the European Union's *Horizon 2020 research and innovative programme* under grant agreement No. 637010



HORIZON 2020

