

Getting to the point: Rapid, high quality point selection and variable point time series for deformation monitoring

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MDIS workshop, October 2017



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UNIVERSITY OF LEEDS

Why Sentinel-1 is a game changer?

- Systematic acquisitions, high duty cycle
- Large image footprints:
~250 x 250-1000 km
- Designed for InSAR
- 20 year operational program
- Free, full and open data policy



Why Sentinel-1 is a game changer?

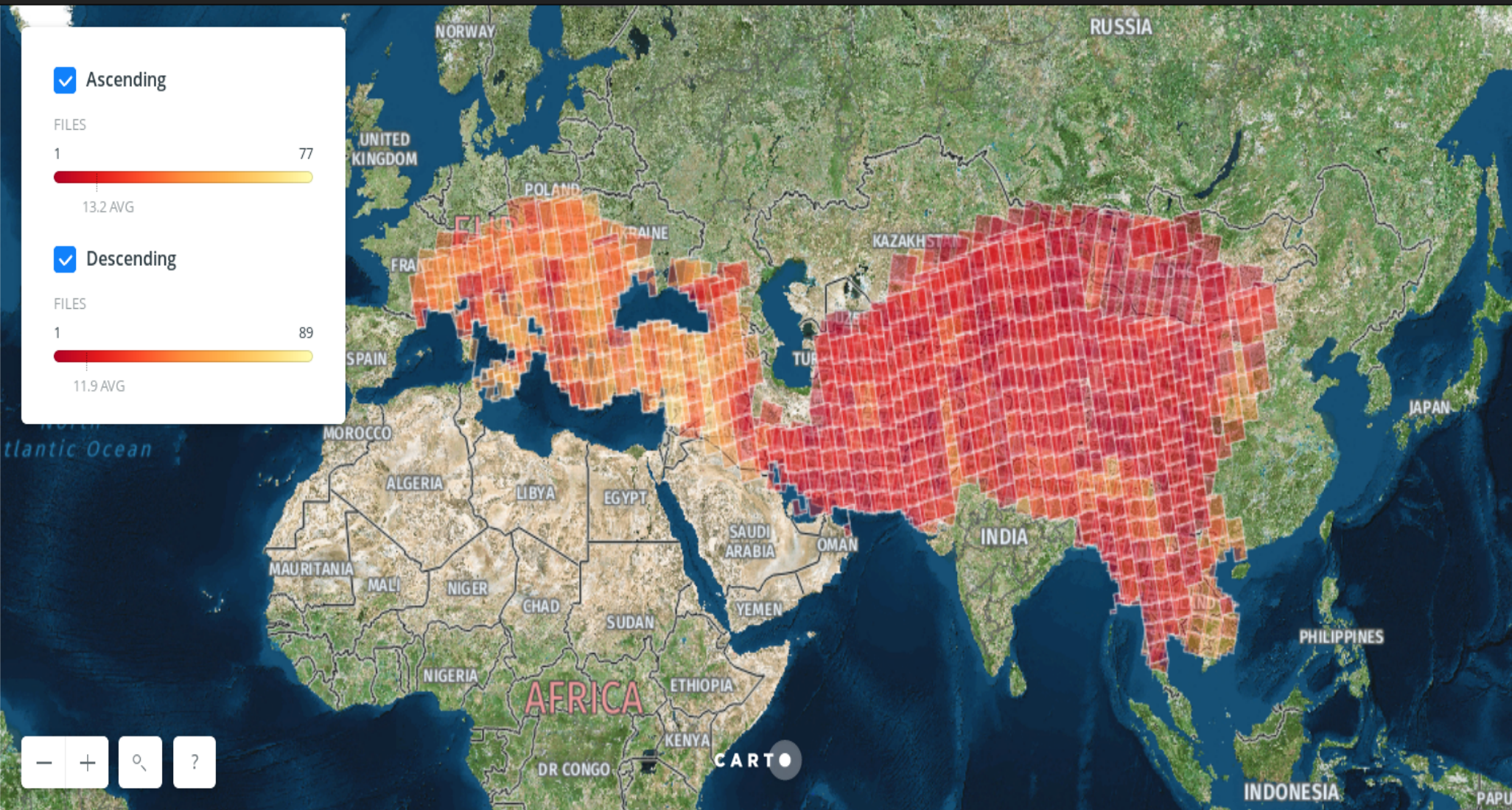
- Systematic acquisitions, high duty cycle
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~250 x 250-1000 km
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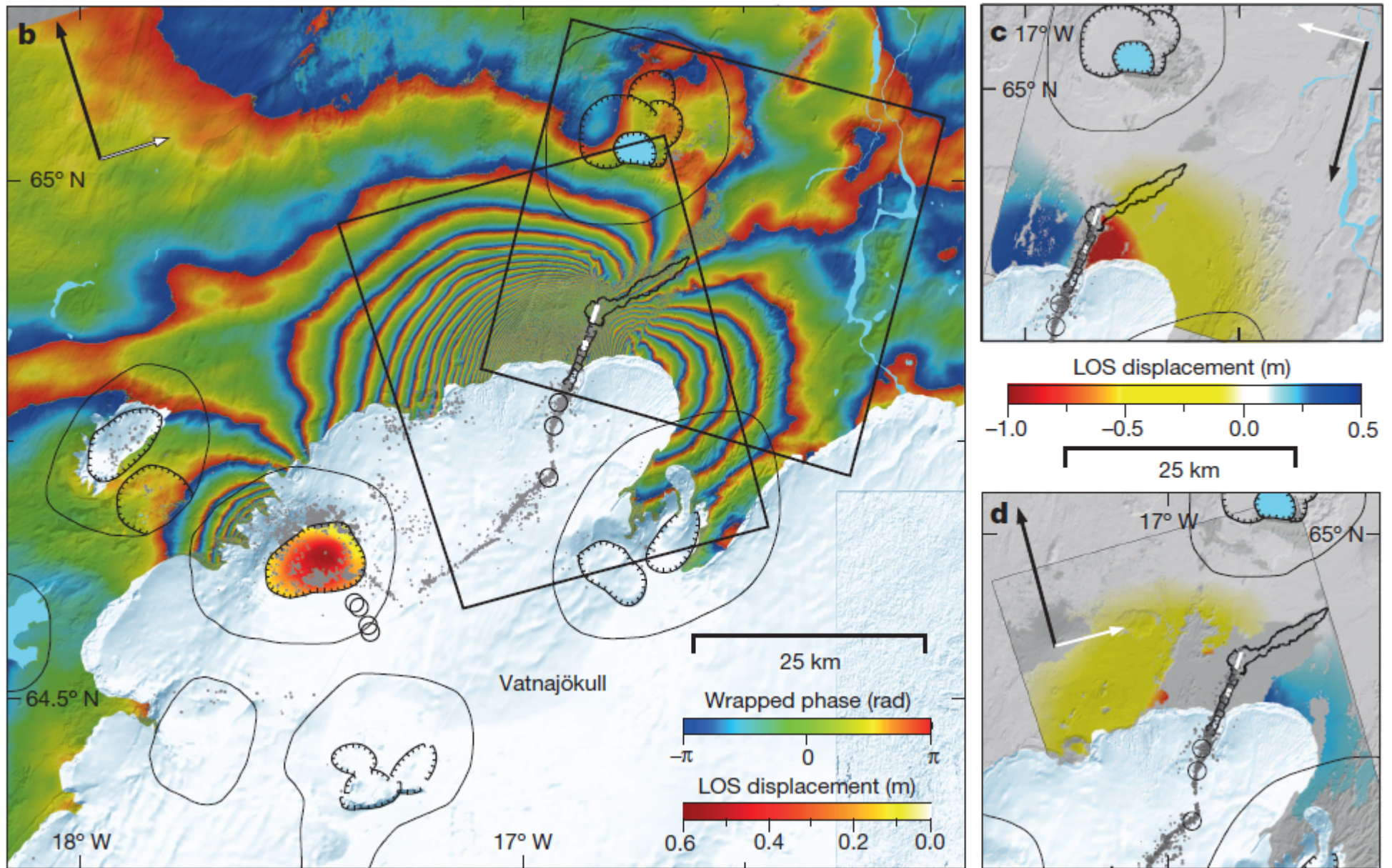
Sentinel-1 data volumes



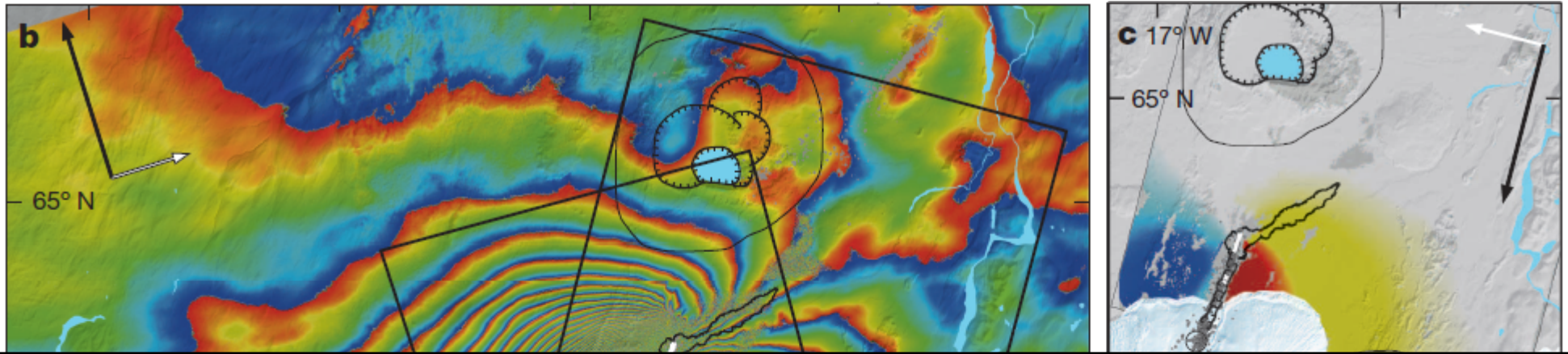
COMET-LiCS Sentinel-1 InSAR portal



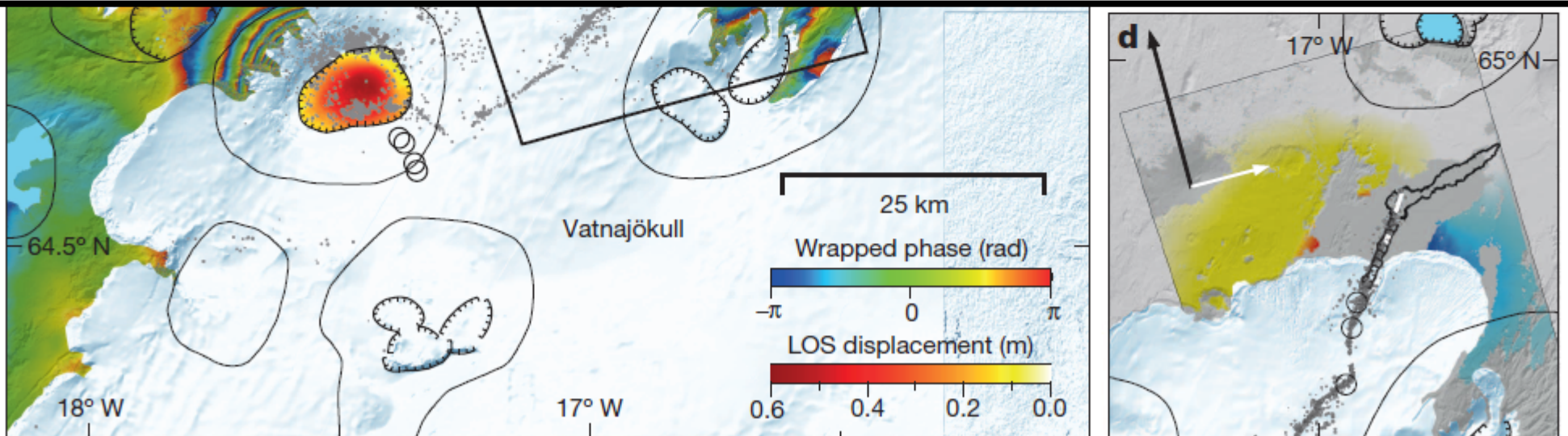
Volcanic deformation monitoring



Volcanic deformation monitoring



Differential interferogram unwrapping relies on coherence estimate



Strain mapping

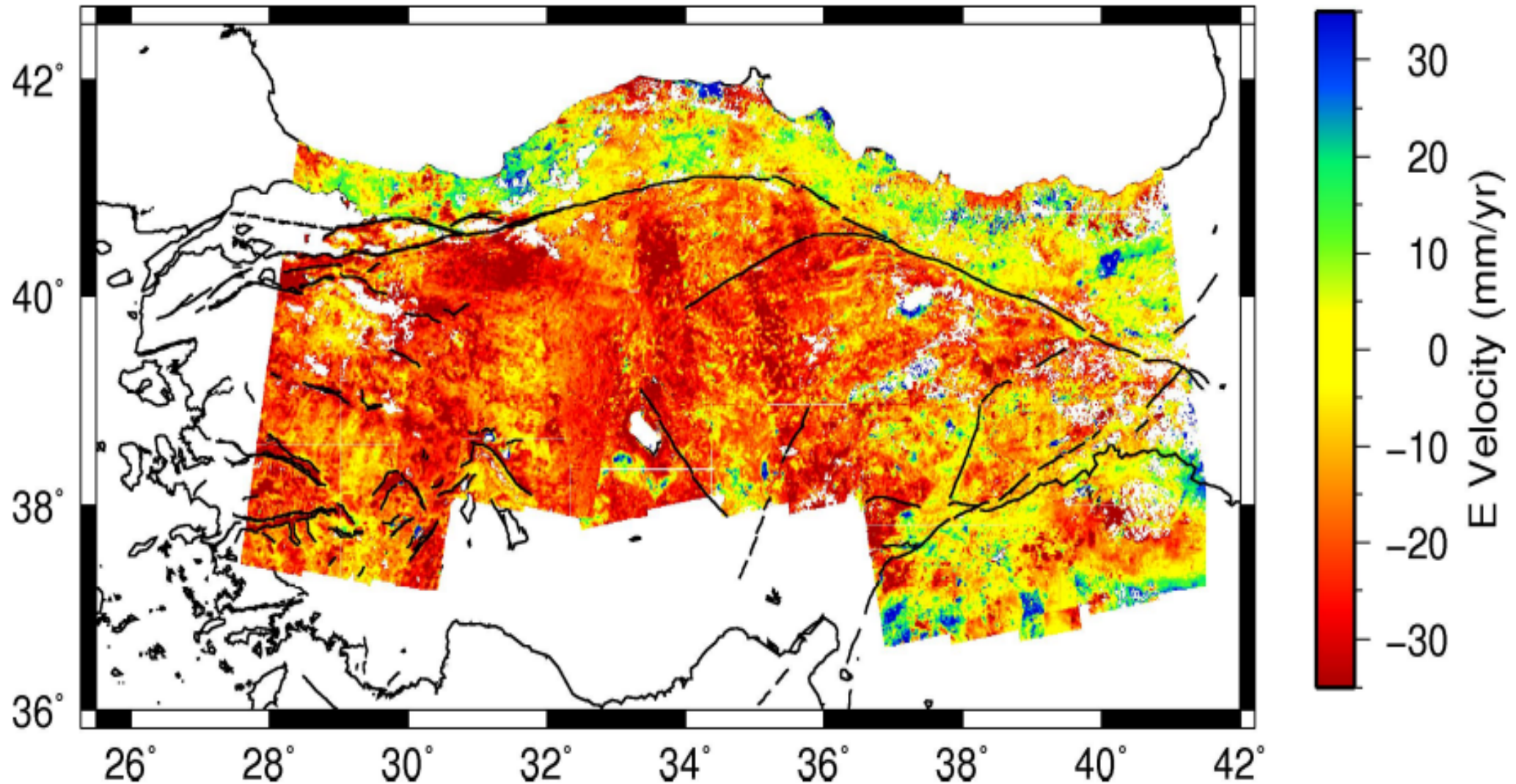
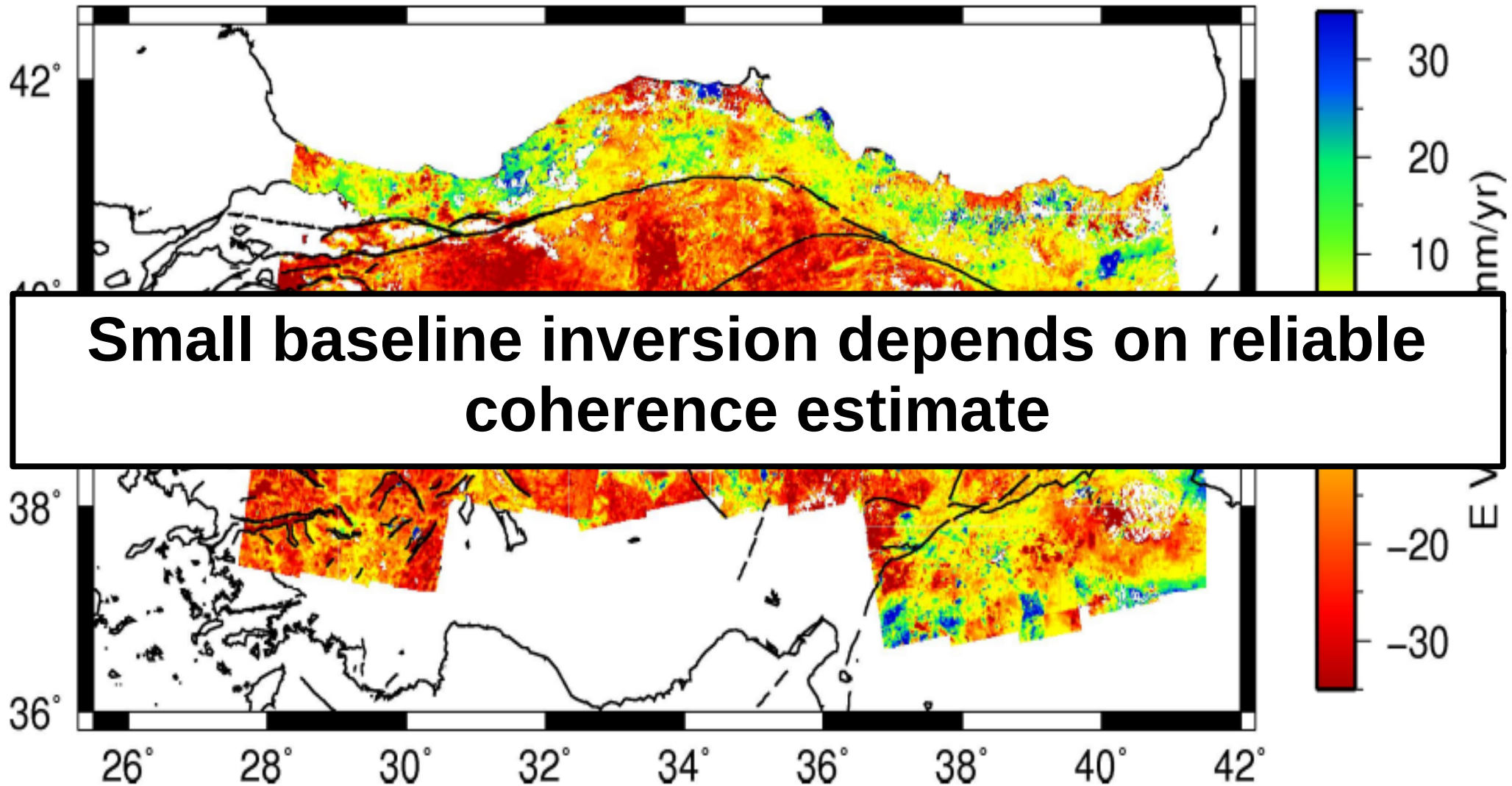


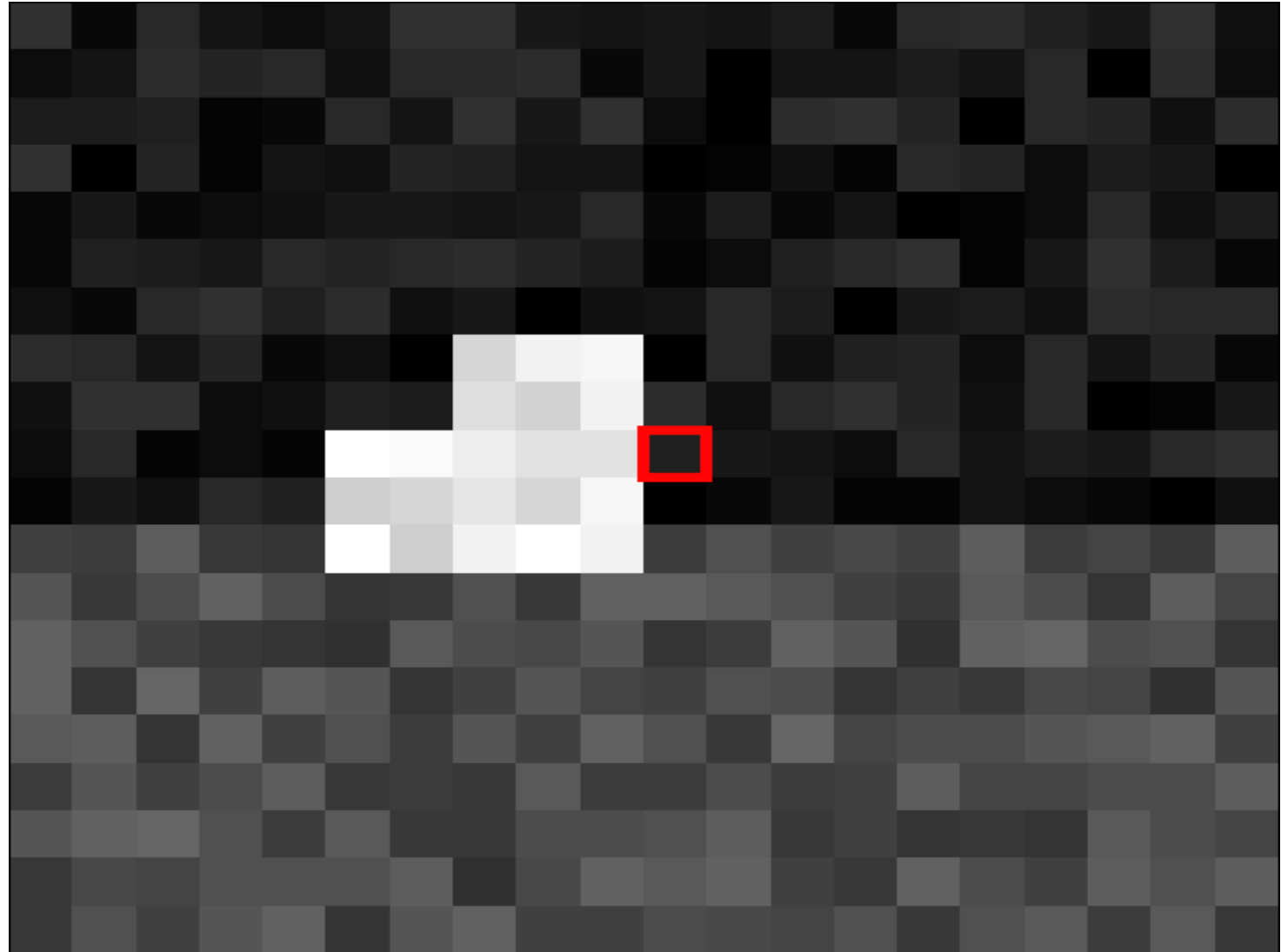
Image from Rich Walters

Strain mapping



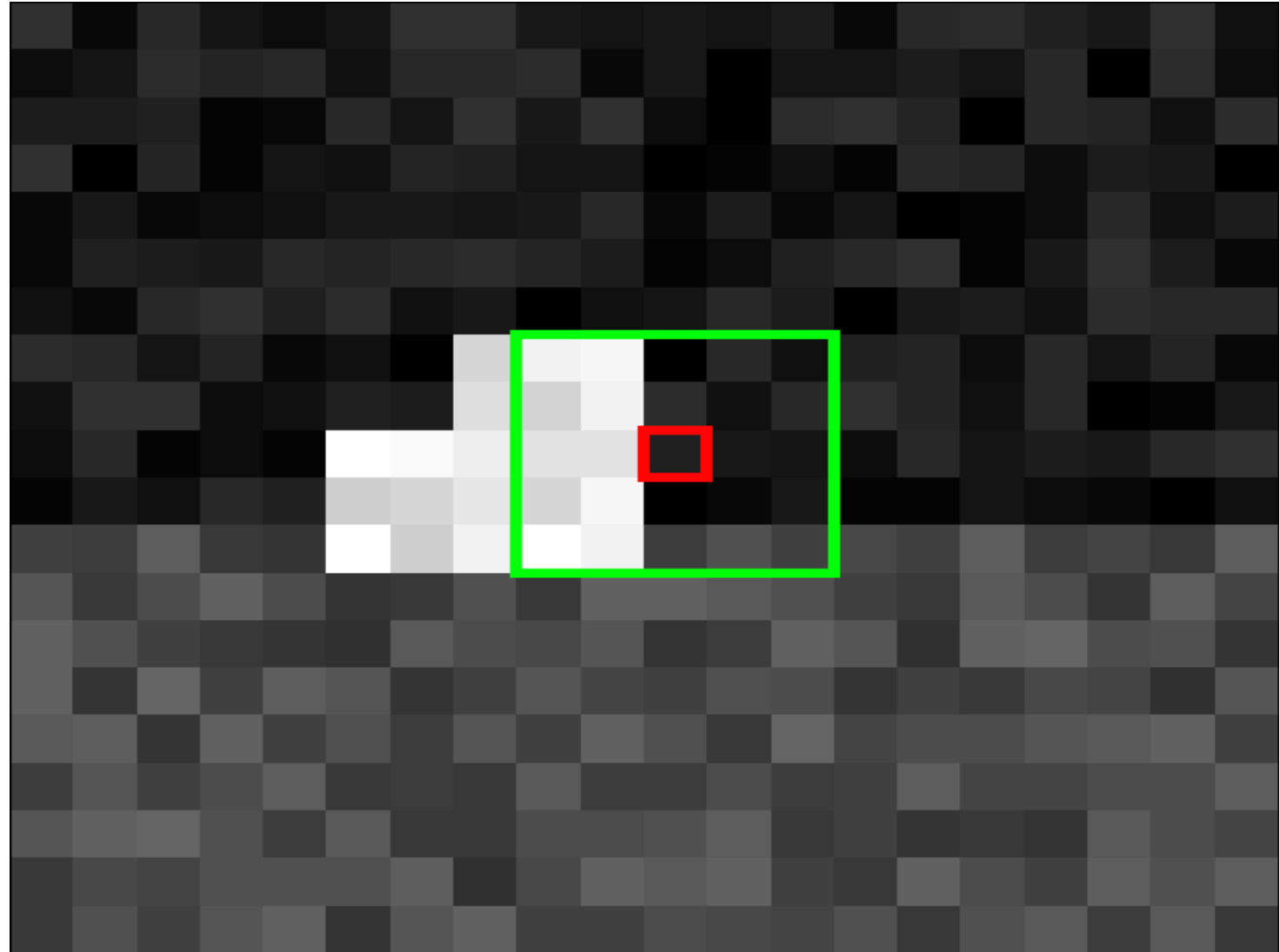
Boxcar coherence

- Traditional
- Fast
- Flexible



Boxcar coherence

- Traditional
- Fast
- Flexible

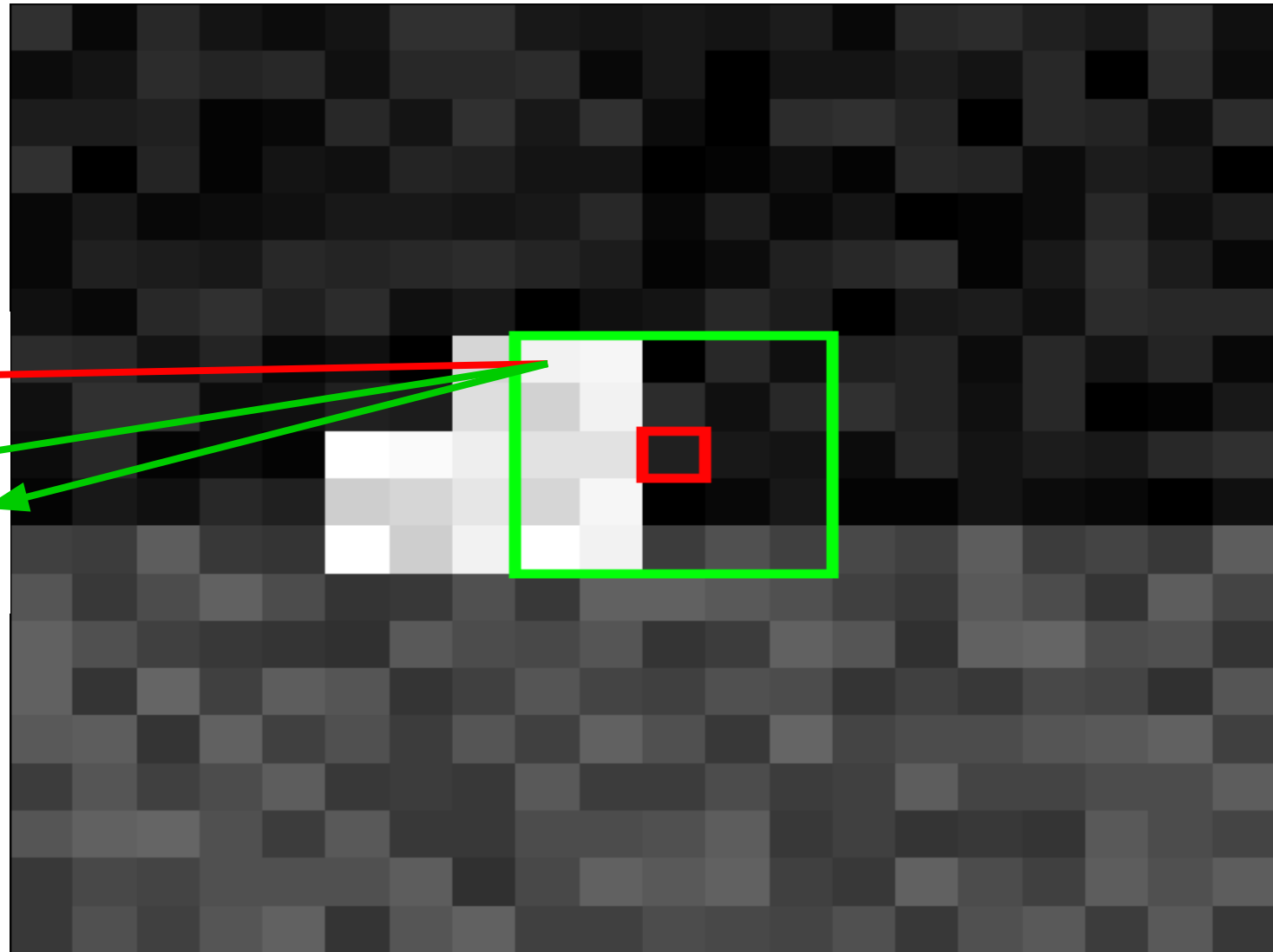


Boxcar coherence

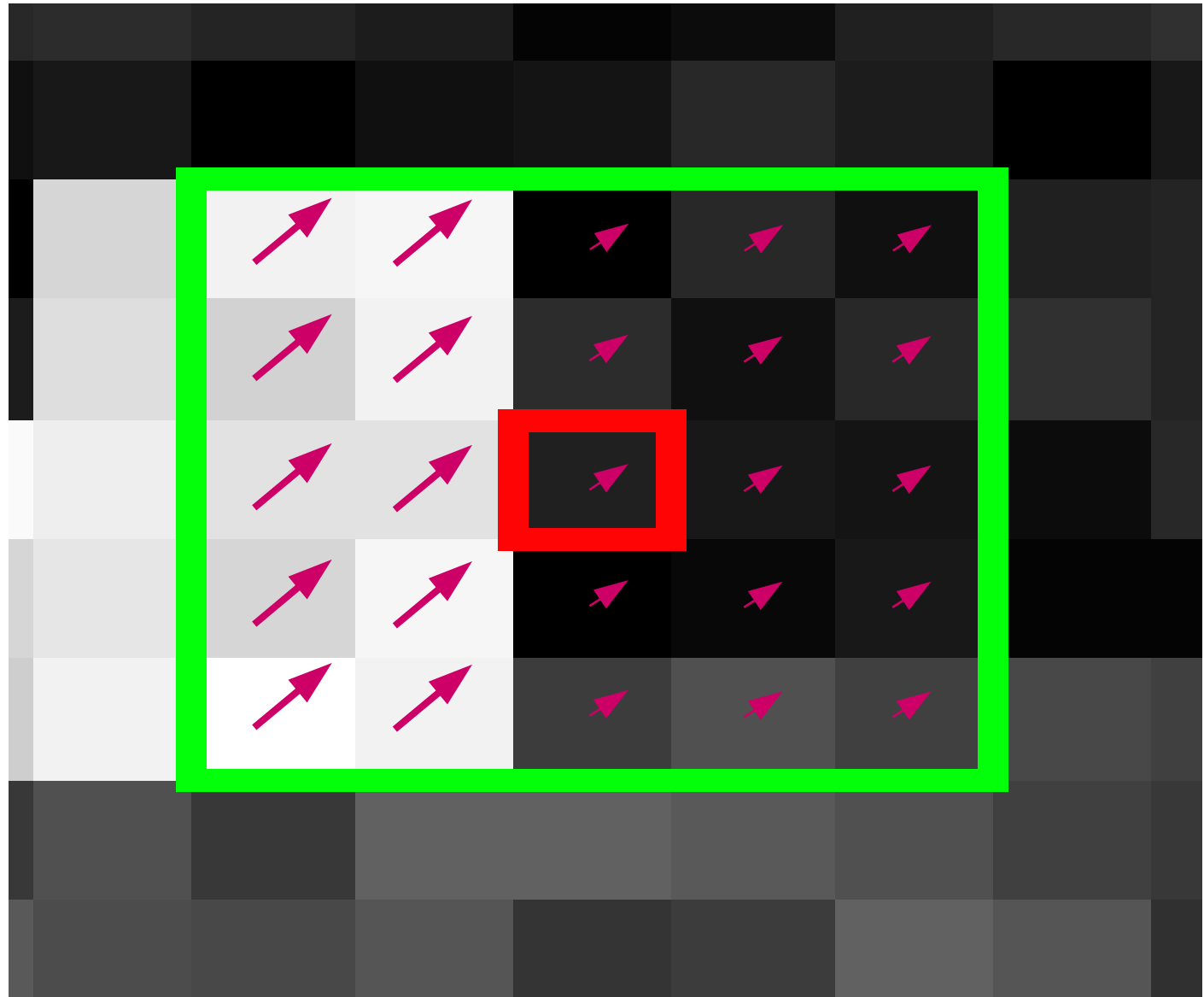
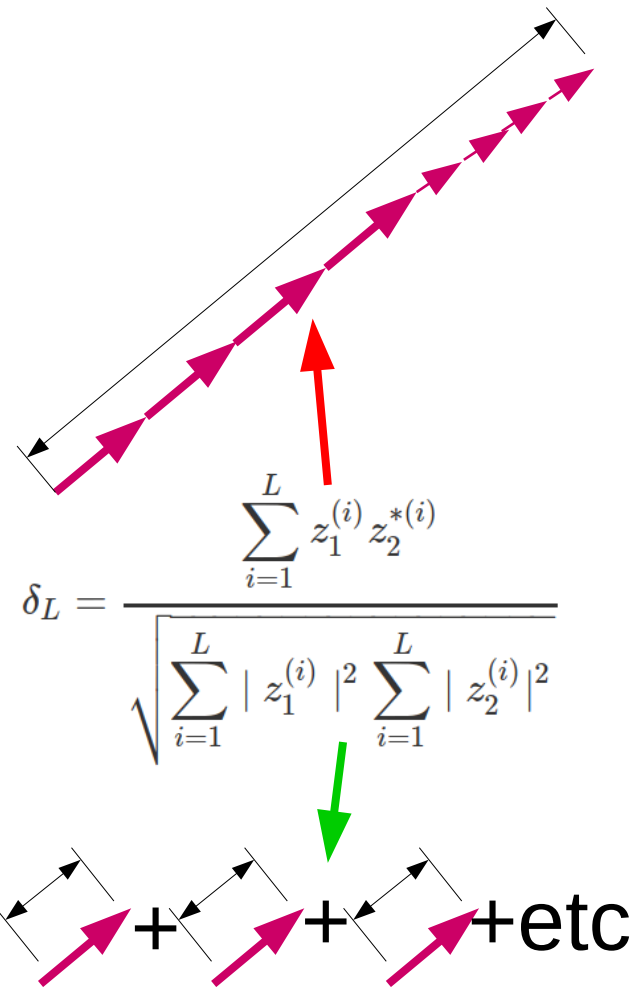
Interferometric
signal for each pixel
(phase + amplitude!)

$$\delta_L = \frac{\sum_{i=1}^L z_1^{(i)} z_2^{*(i)}}{\sqrt{\sum_{i=1}^L |z_1^{(i)}|^2 \sum_{i=1}^L |z_2^{(i)}|^2}}$$

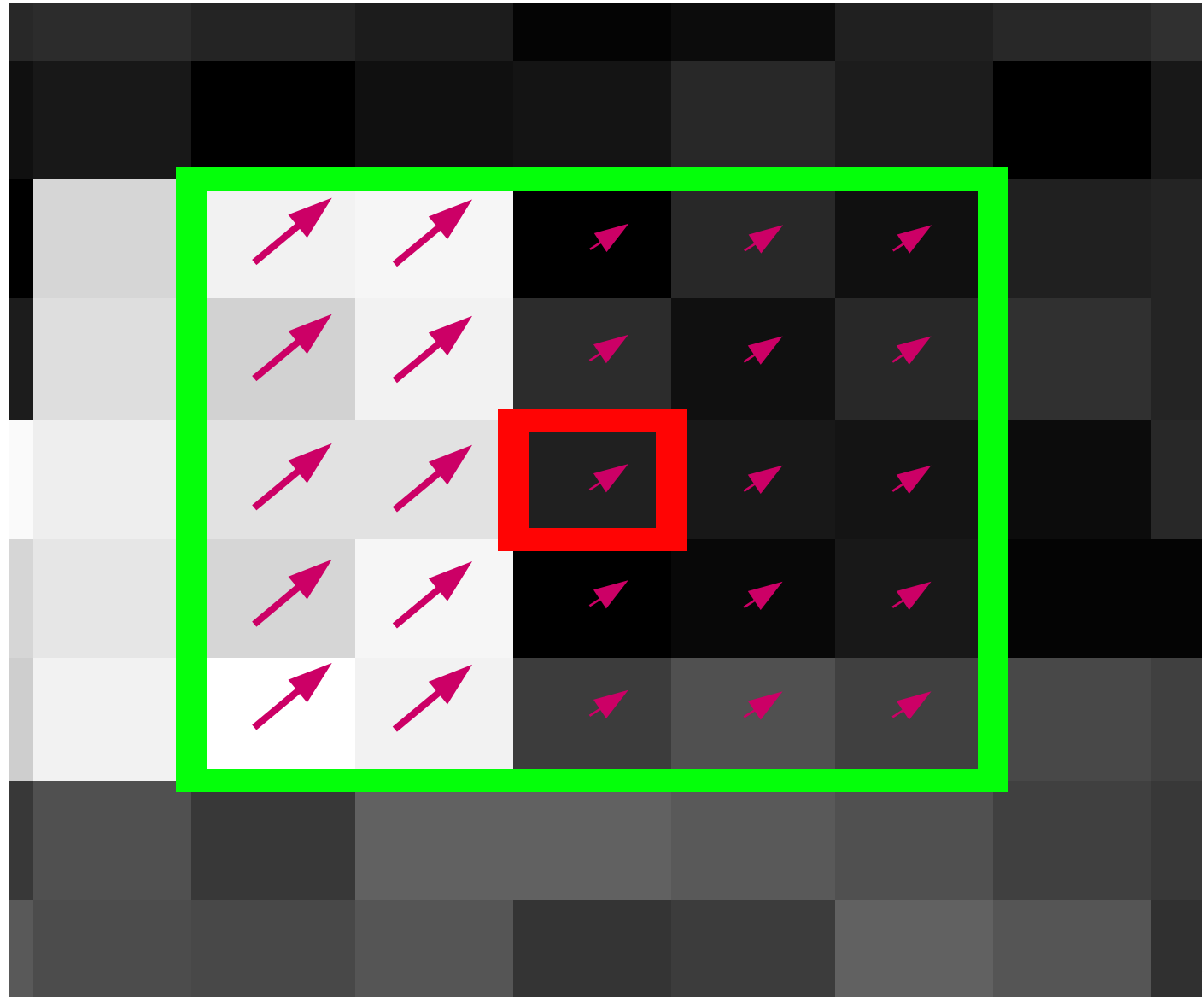
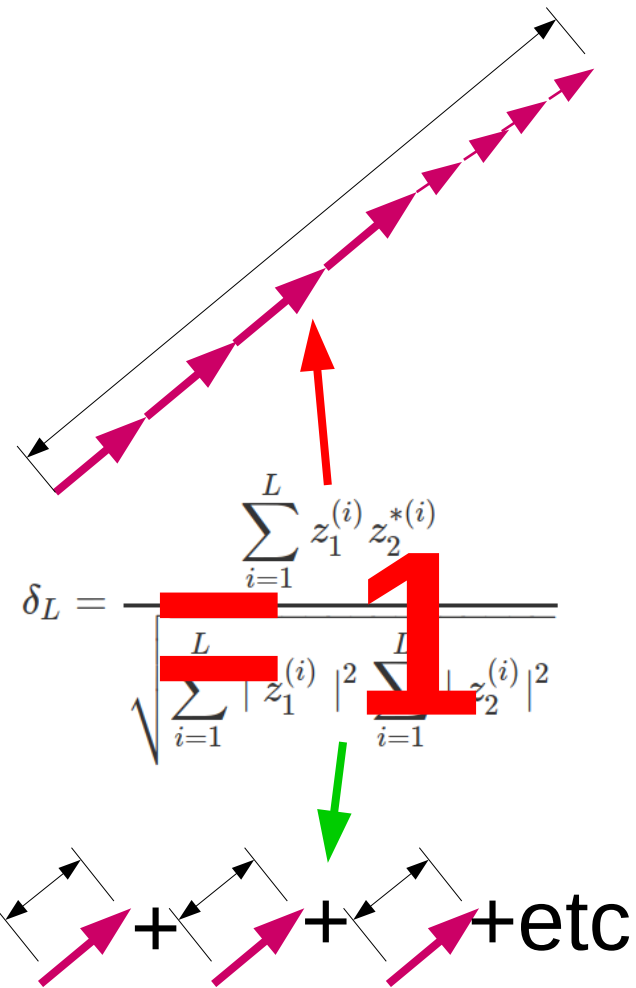
Amplitude for each
pixel



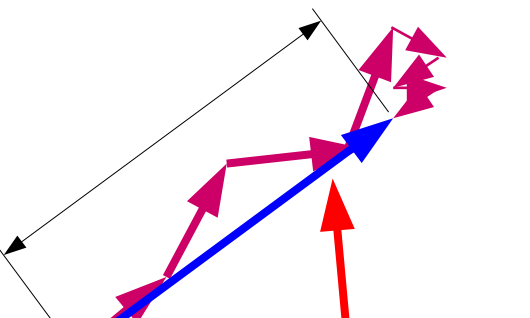
Boxcar coherence



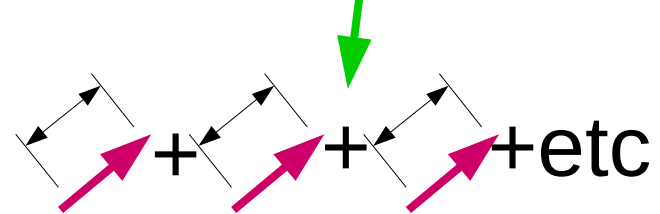
Boxcar coherence



Boxcar coherence

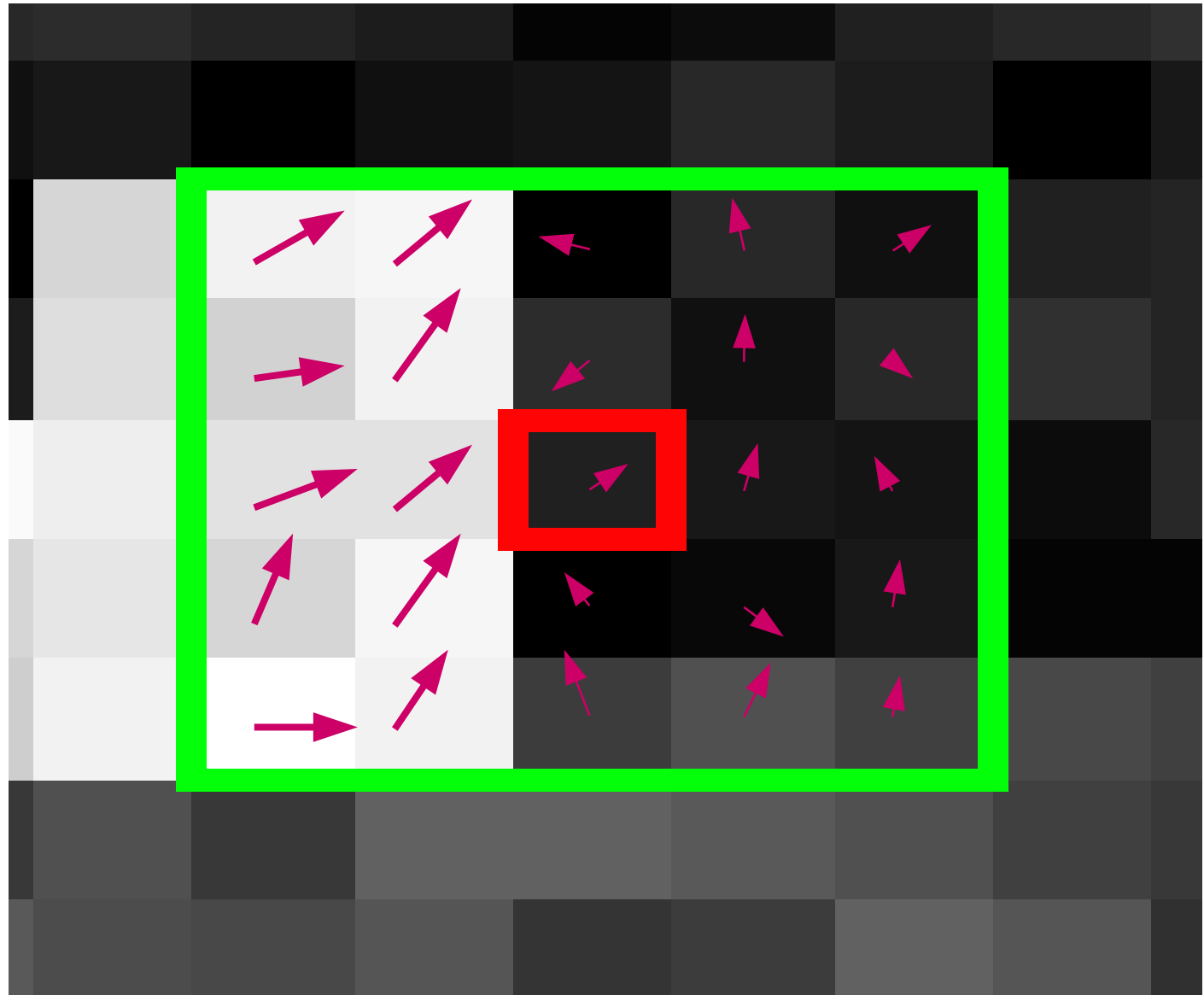


A diagram showing a blue vector representing the sum of several pink vectors. A red arrow points from the equation below to the blue vector.

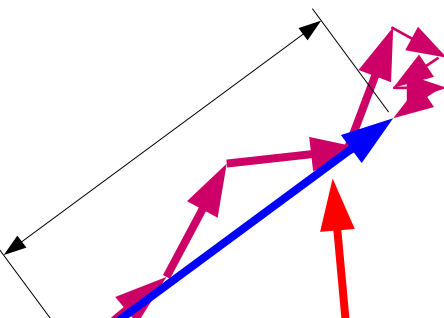
$$\delta_L = \frac{\sum_{i=1}^L z_1^{(i)} z_2^{*(i)}}{\sqrt{\sum_{i=1}^L |z_1^{(i)}|^2 \sum_{i=1}^L |z_2^{(i)}|^2}}$$


A diagram showing three pink vectors being added together, with a green arrow pointing from the equation above to the first vector.

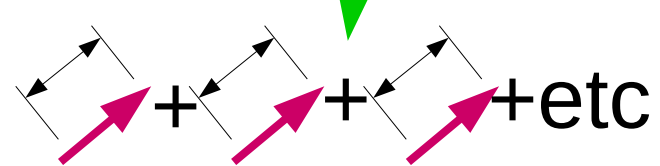
+ + + etc



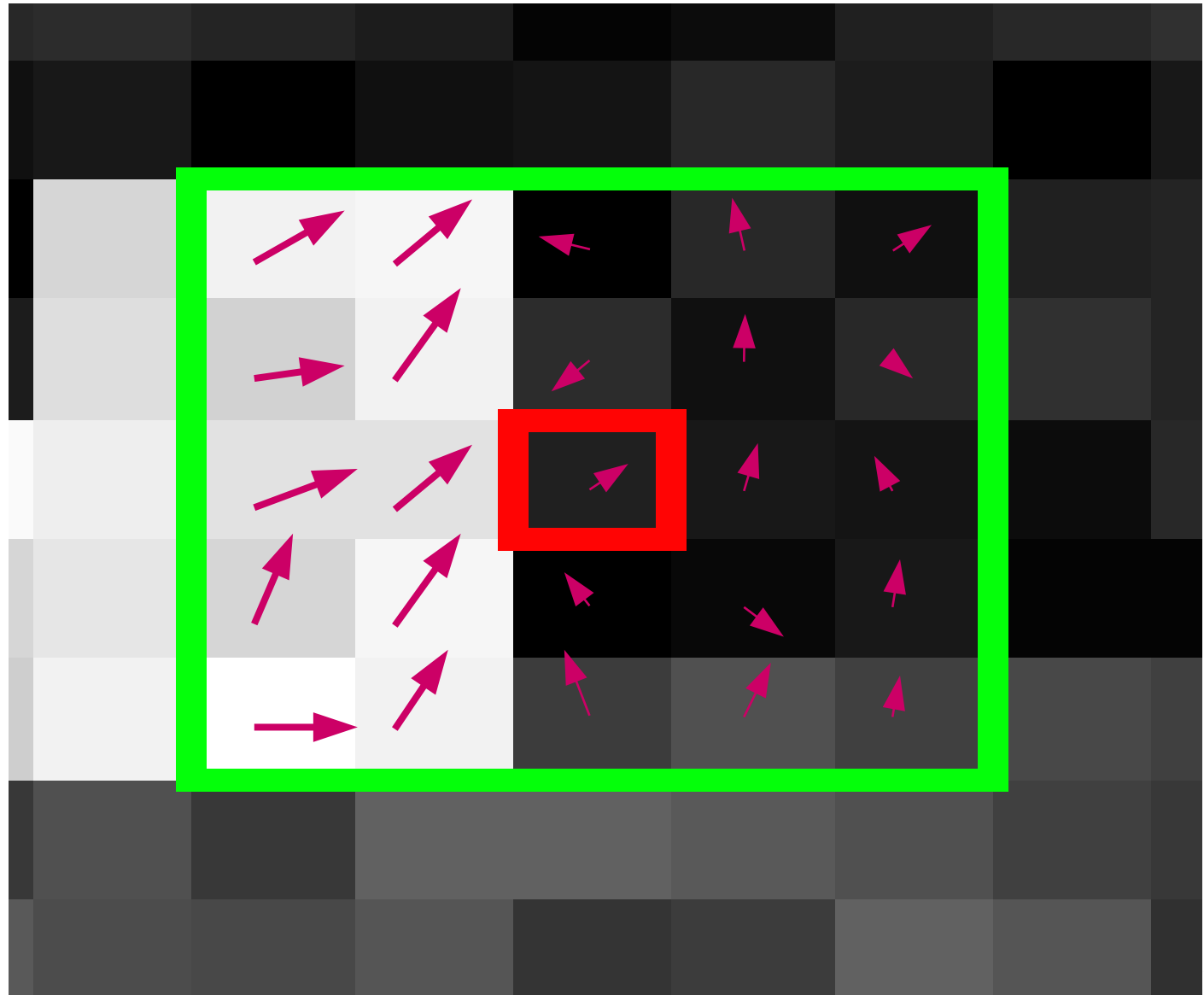
Boxcar coherence



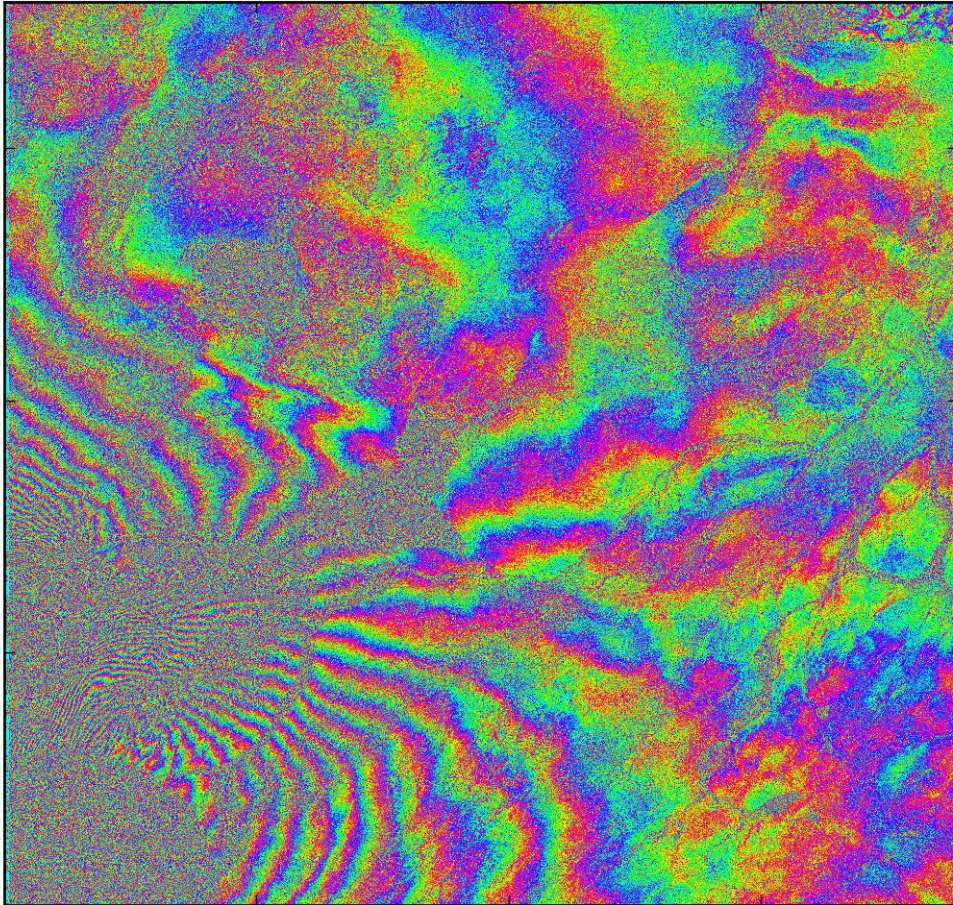
A diagram showing a blue vector and a red vector originating from the same point. A series of pink arrows connects the tip of the red vector to the tip of the blue vector, illustrating the path of a random walk. A double-headed arrow indicates the distance between the tips of the two vectors.

$$\delta_L = \frac{\sum_{i=1}^L z_1^{(i)} z_2^{*(i)}}{\sqrt{\sum_{i=1}^L |z_1^{(i)}|^2 \sum_{i=1}^L |z_2^{(i)}|^2}} = 0.5$$


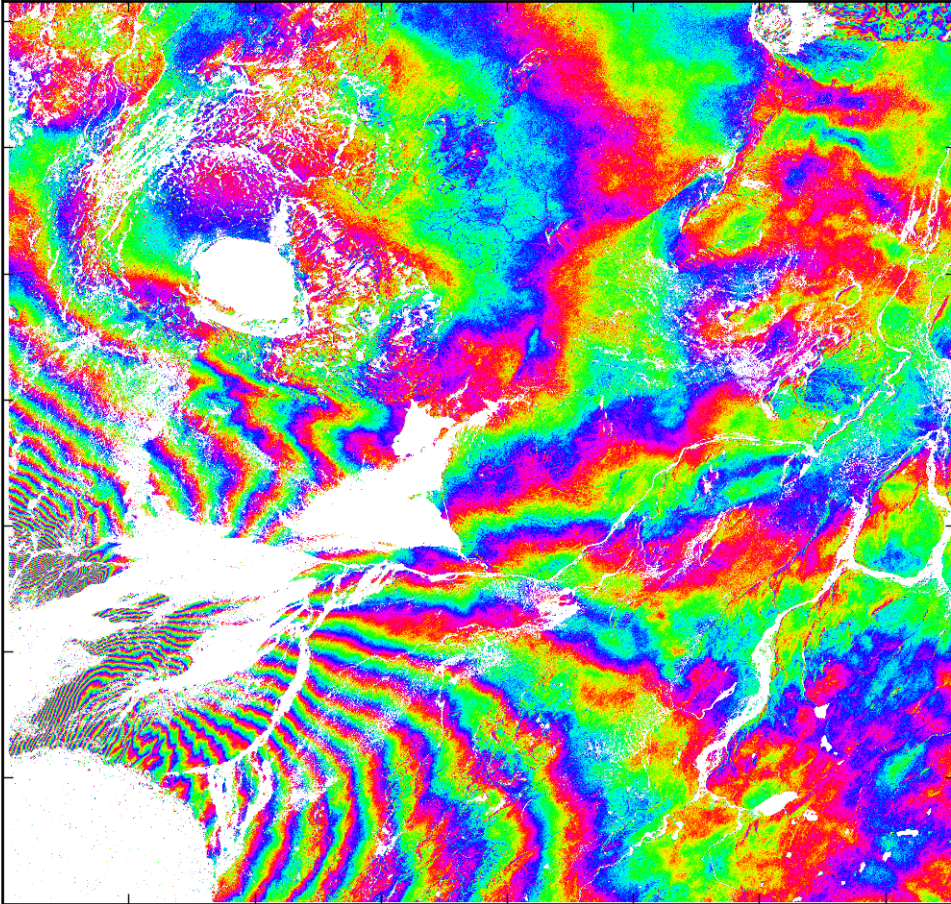
A diagram showing three pink arrows pointing to the right, separated by plus signs, followed by '+etc'. A green arrow points from the '0.5' in the equation above to the first plus sign.



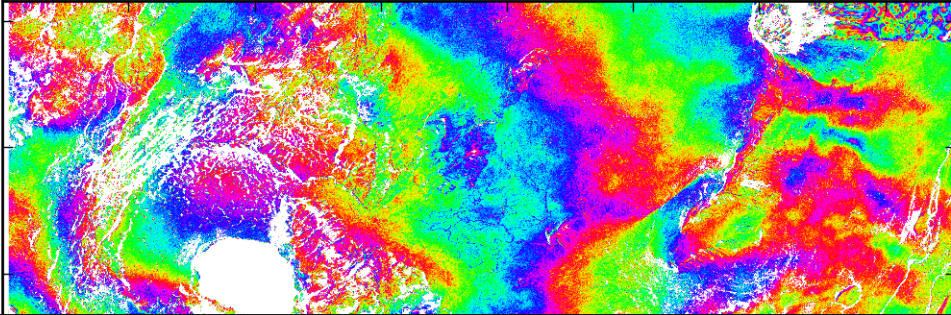
Boxcar coherence example: Bardarbunga rifting



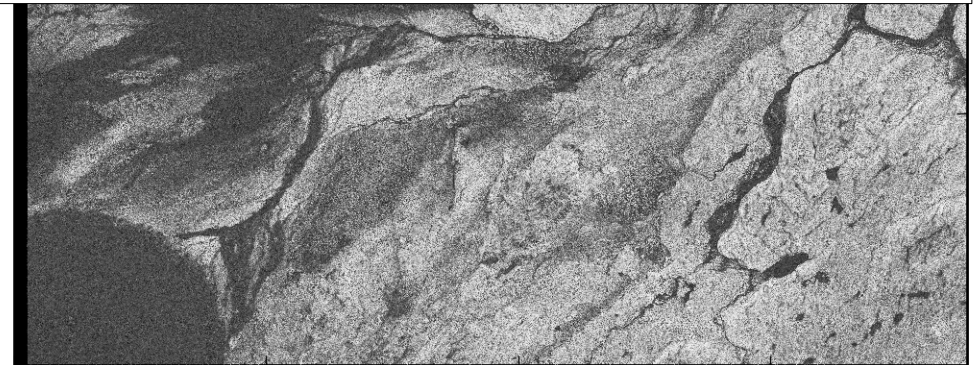
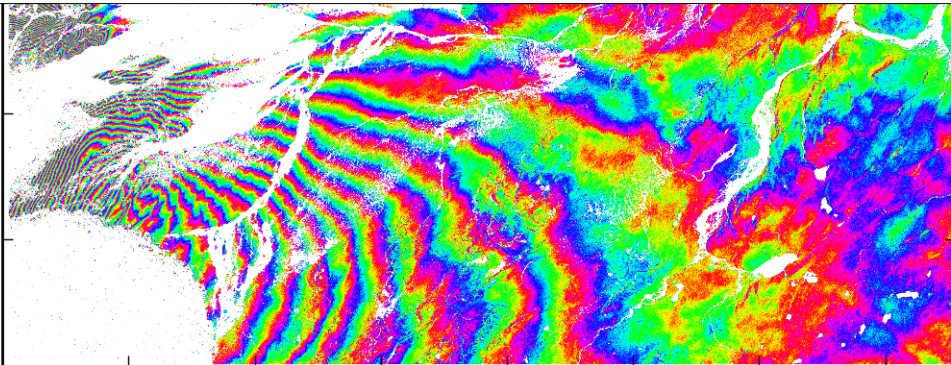
Boxcar coherence example: Bardarbunga rifting



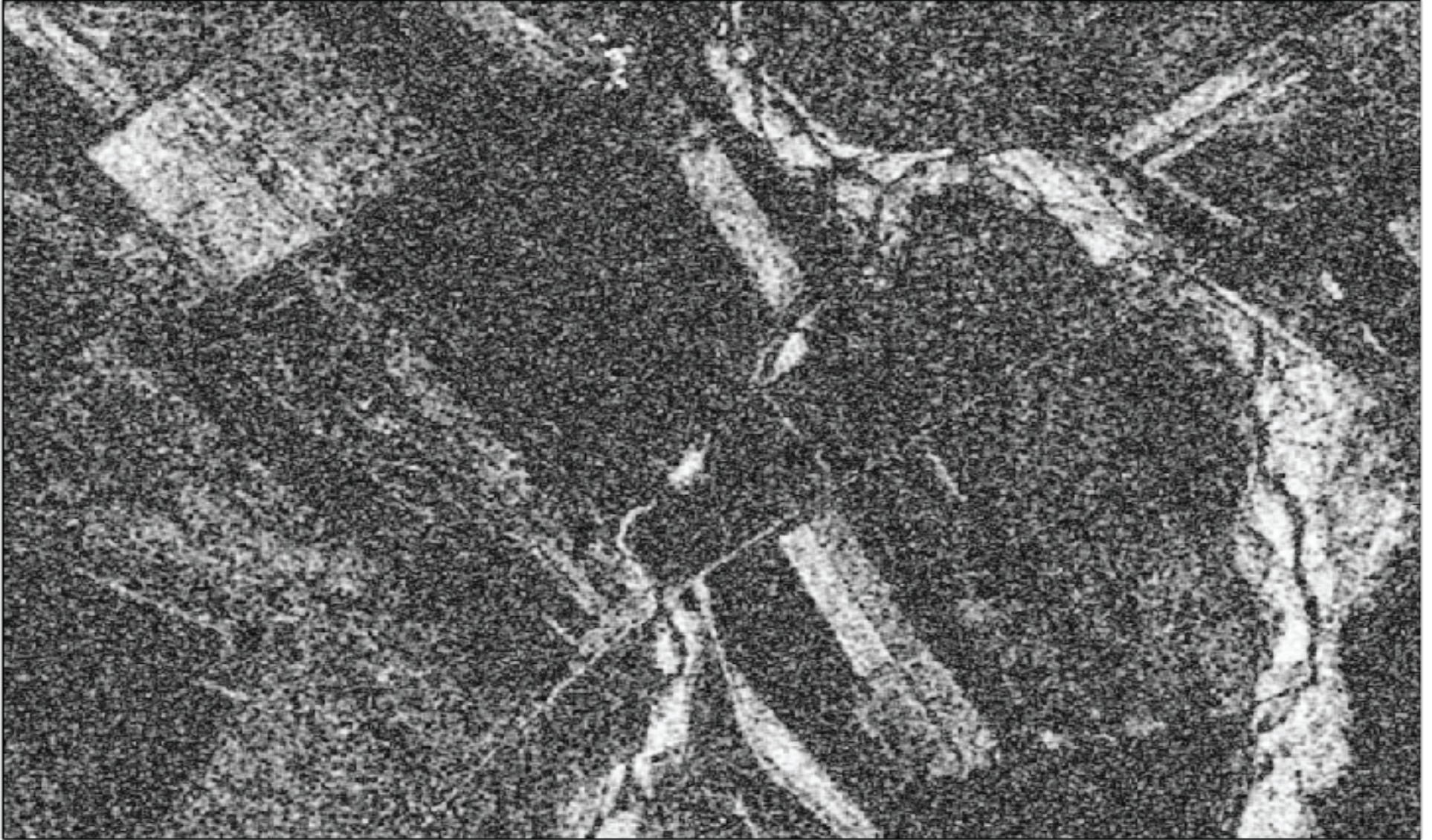
Boxcar coherence example: Bardarbunga rifting



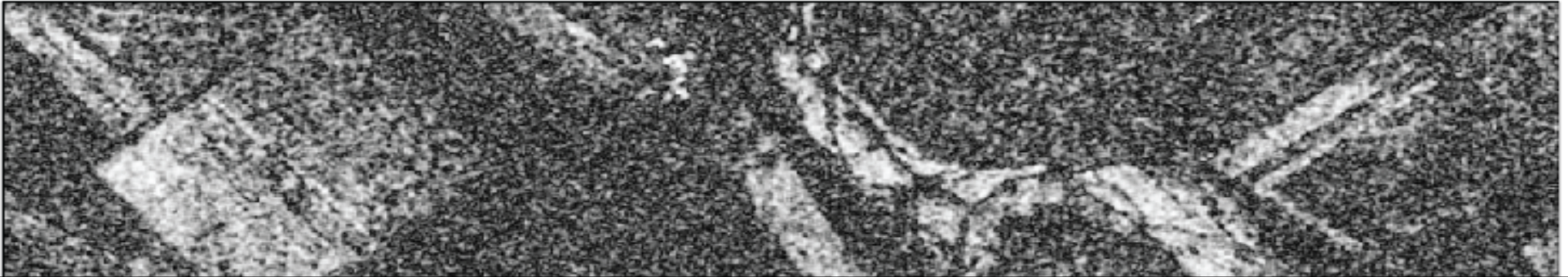
Boxcar coherence can work well as a quick and flexible selection mechanism, but...



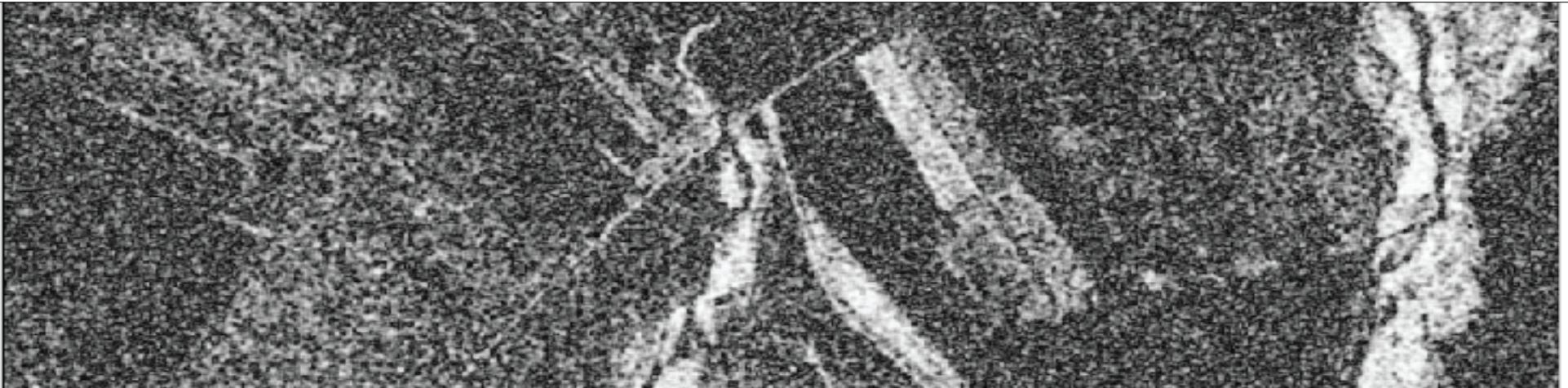
Boxcar coherence issues



Boxcar coherence issues

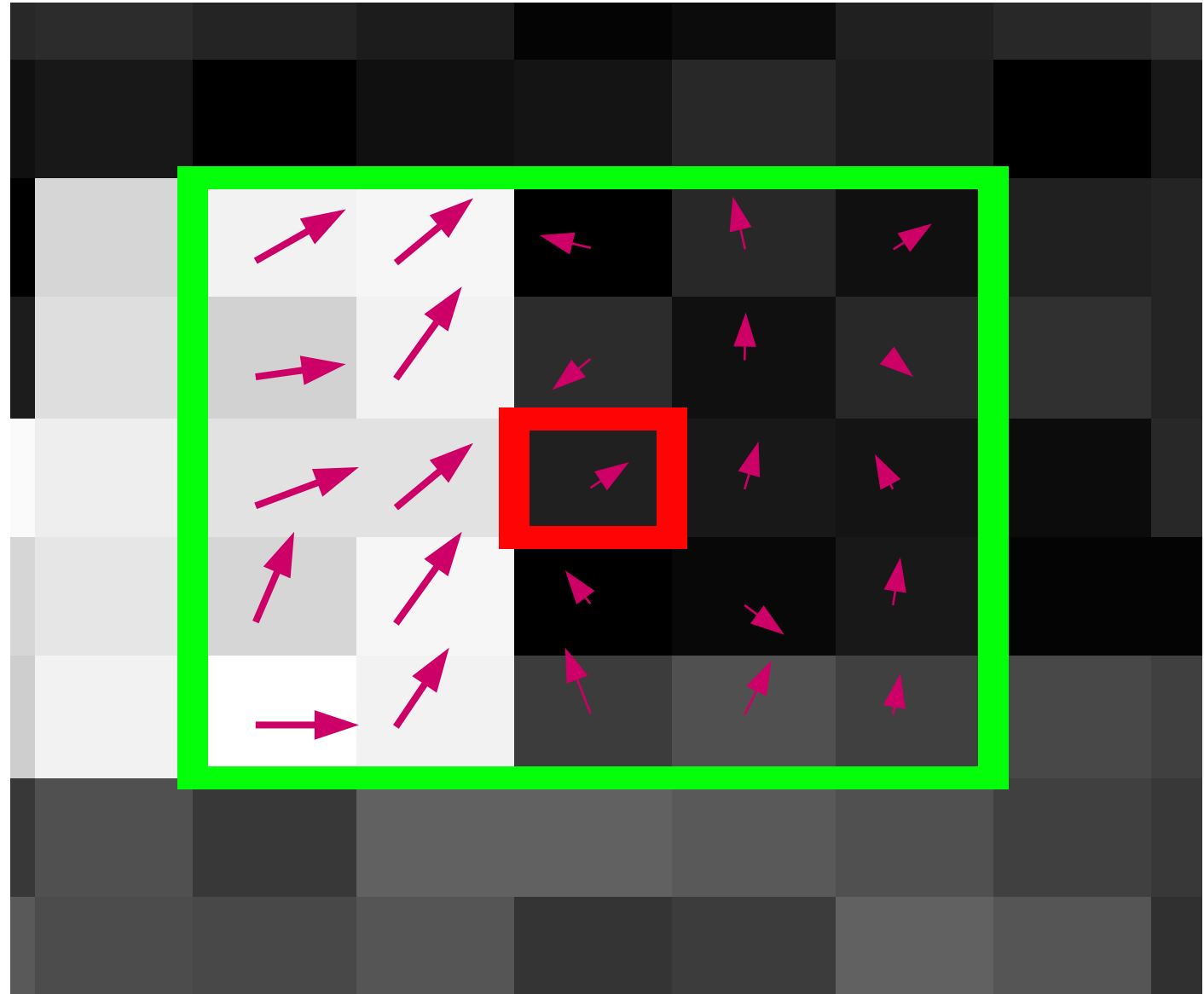
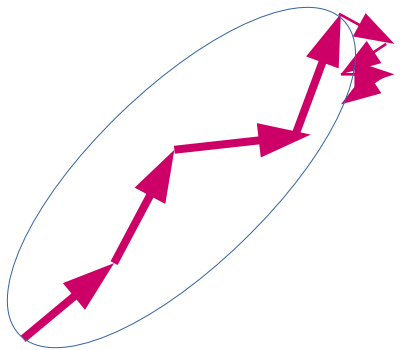


Boxcar coherence estimate tends to smear out features, as well as having many erroneously high estimates in incoherent areas by chance.



Boxcar coherence smearing

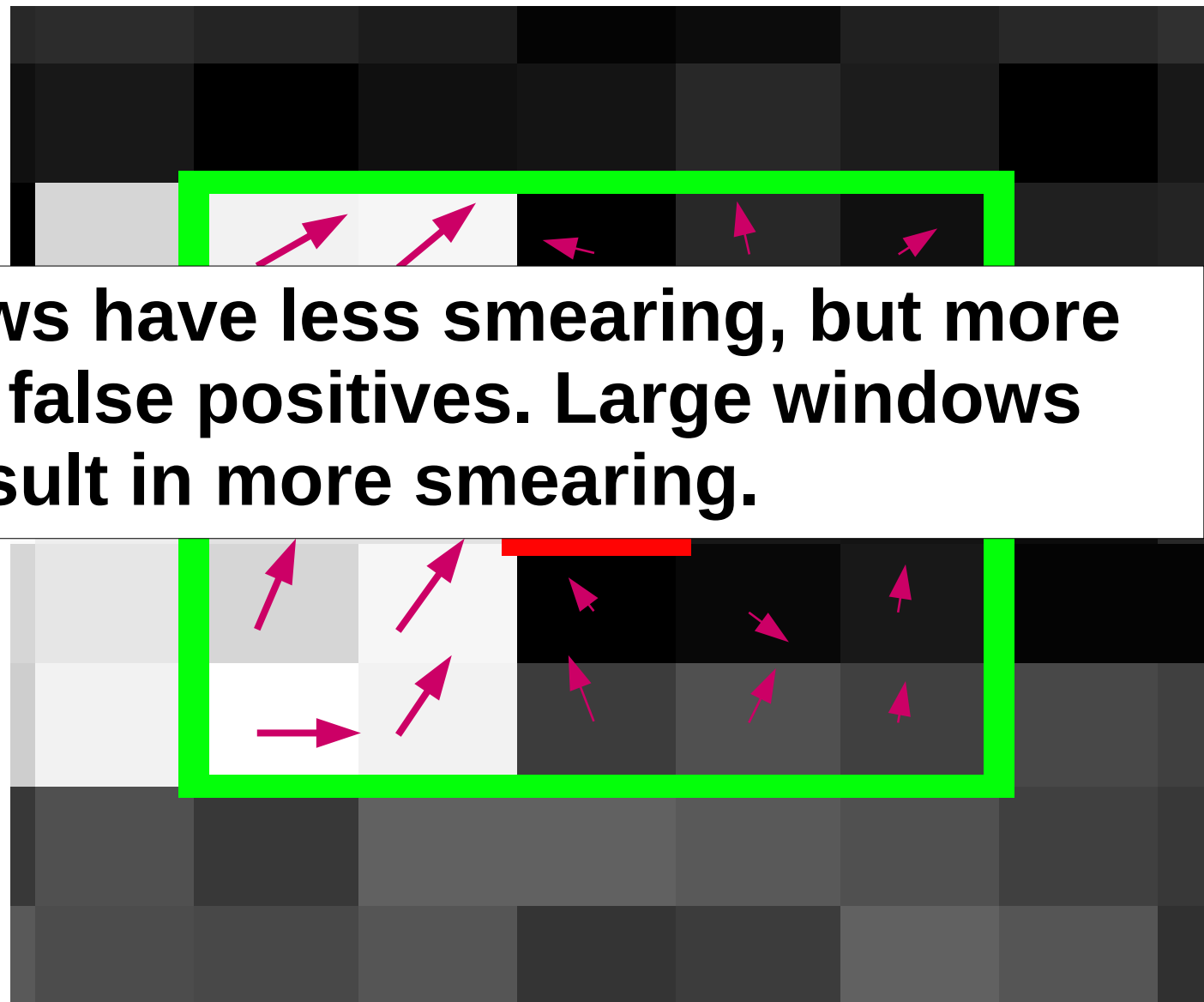
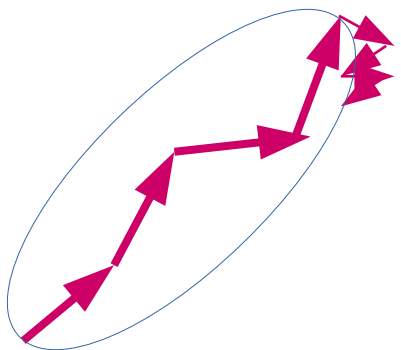
Bright
targets
dominate
the
ensemble!



Boxcar coherence smearing

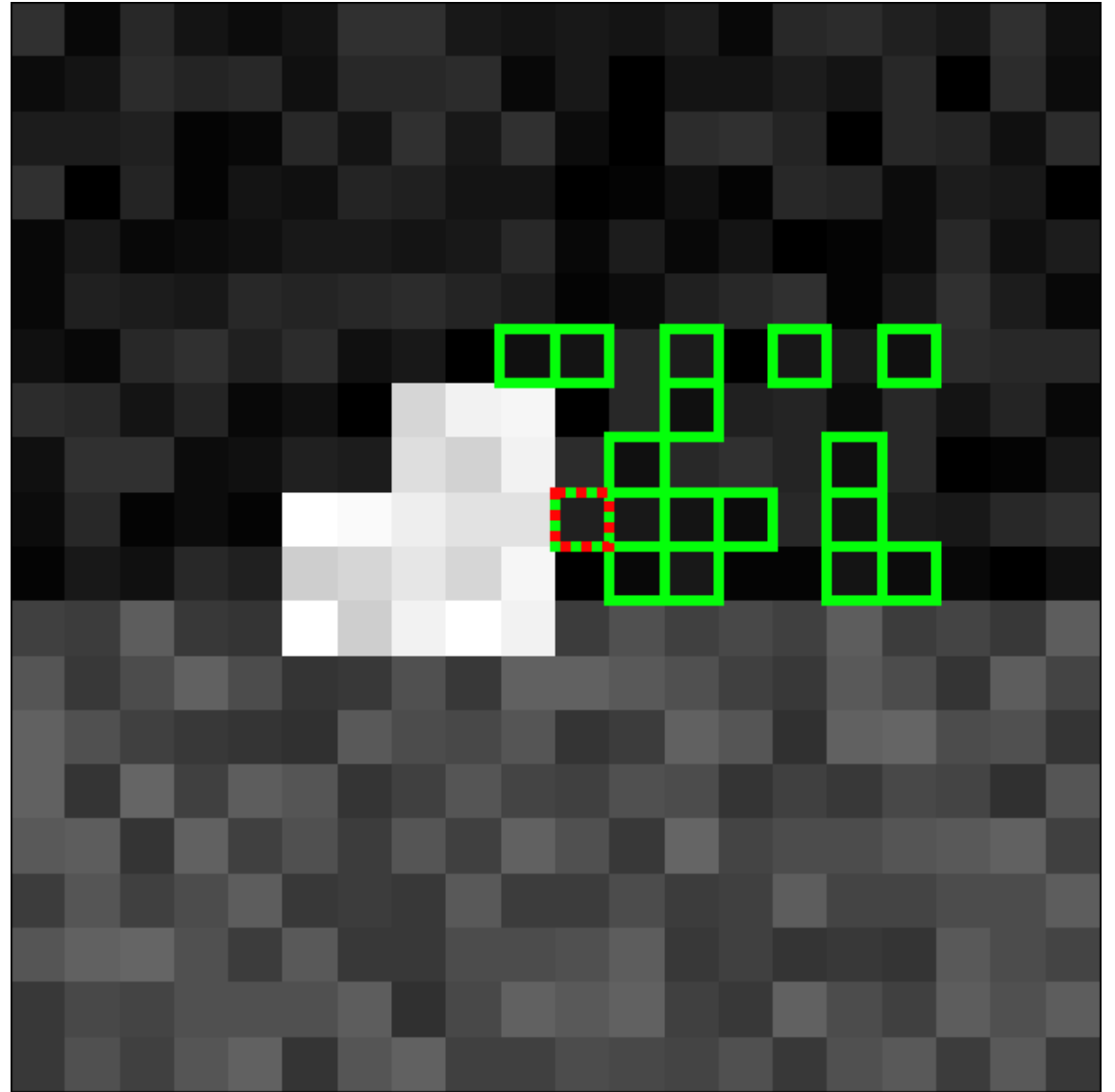
Bright
targets
dominate

Small windows have less smearing, but more sensitive to false positives. Large windows result in more smearing.



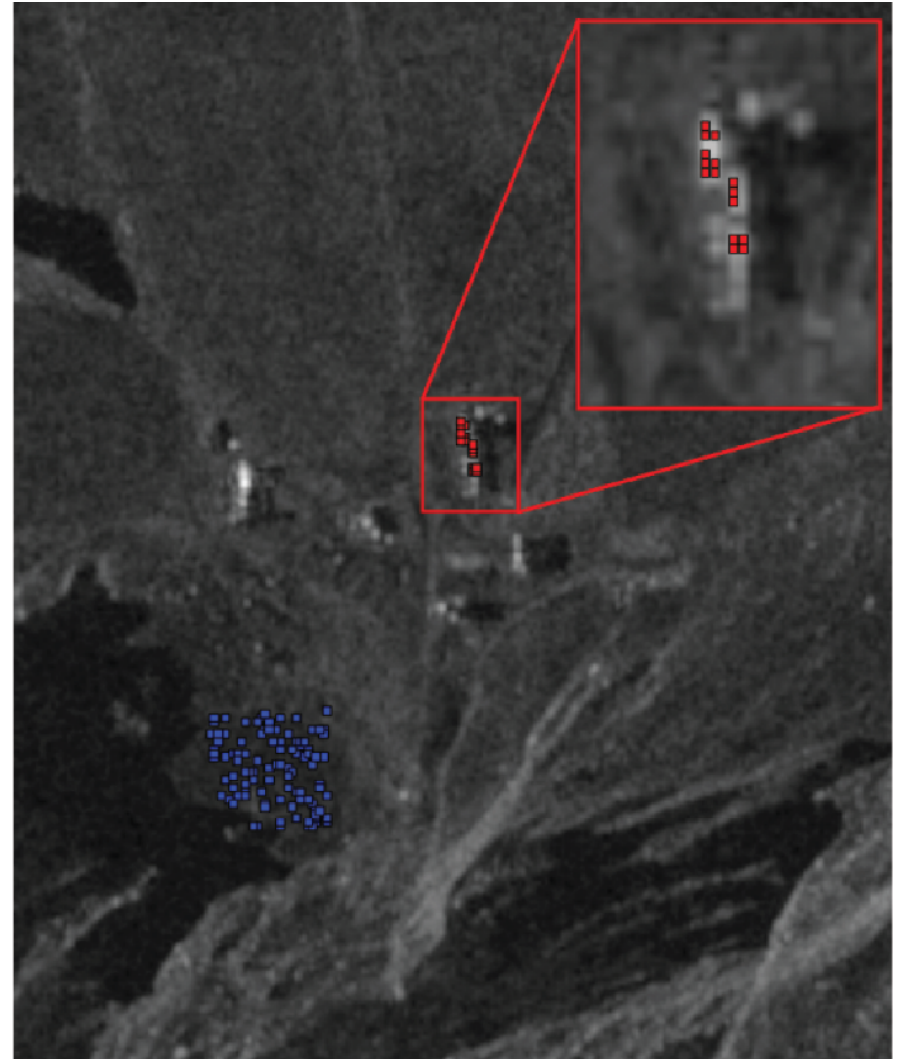
Sibling based coherence

- Use only nearby pixels with similar behaviour through time (“siblings”)
- We use amplitude statistics through time as an indicator



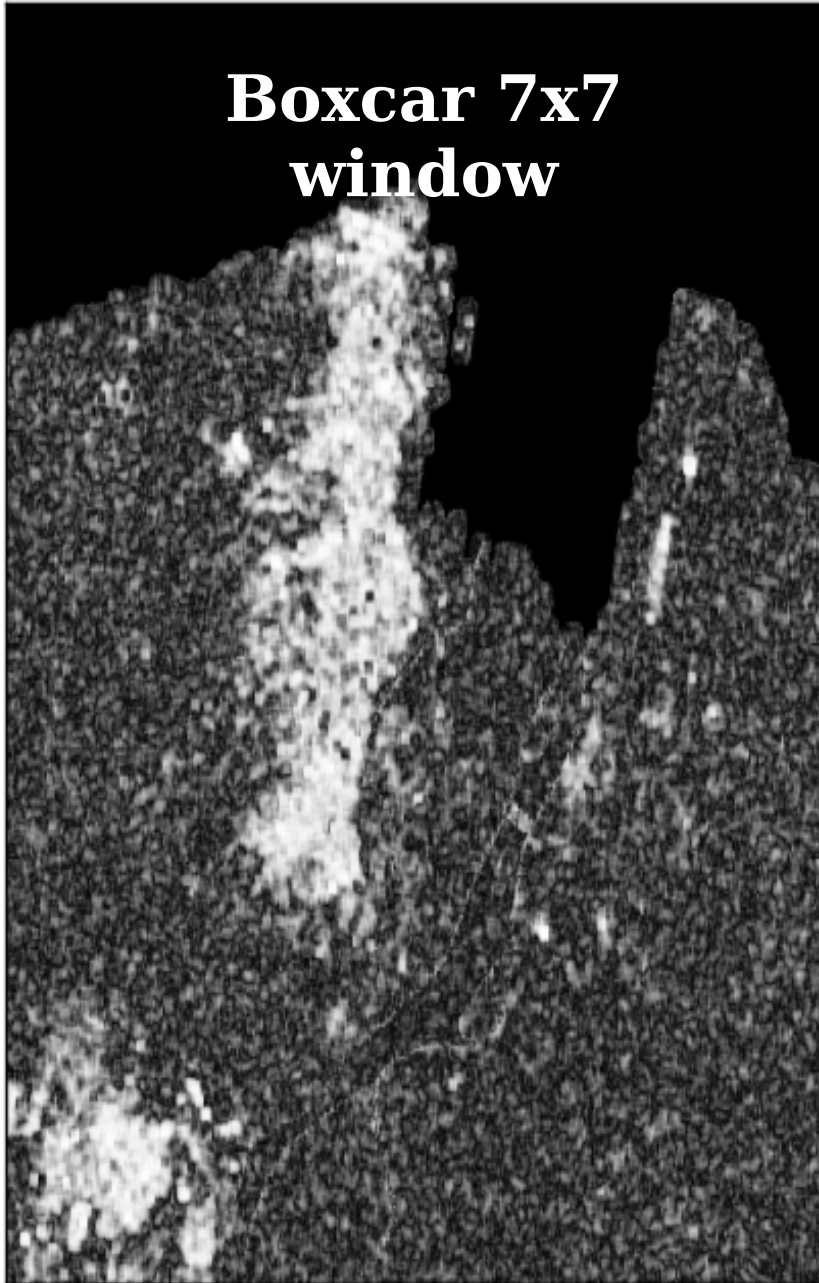
Sibling identification

- Tendency to select fewer, closely grouped siblings for strong scatterers, many spread out siblings for poorer scatterers

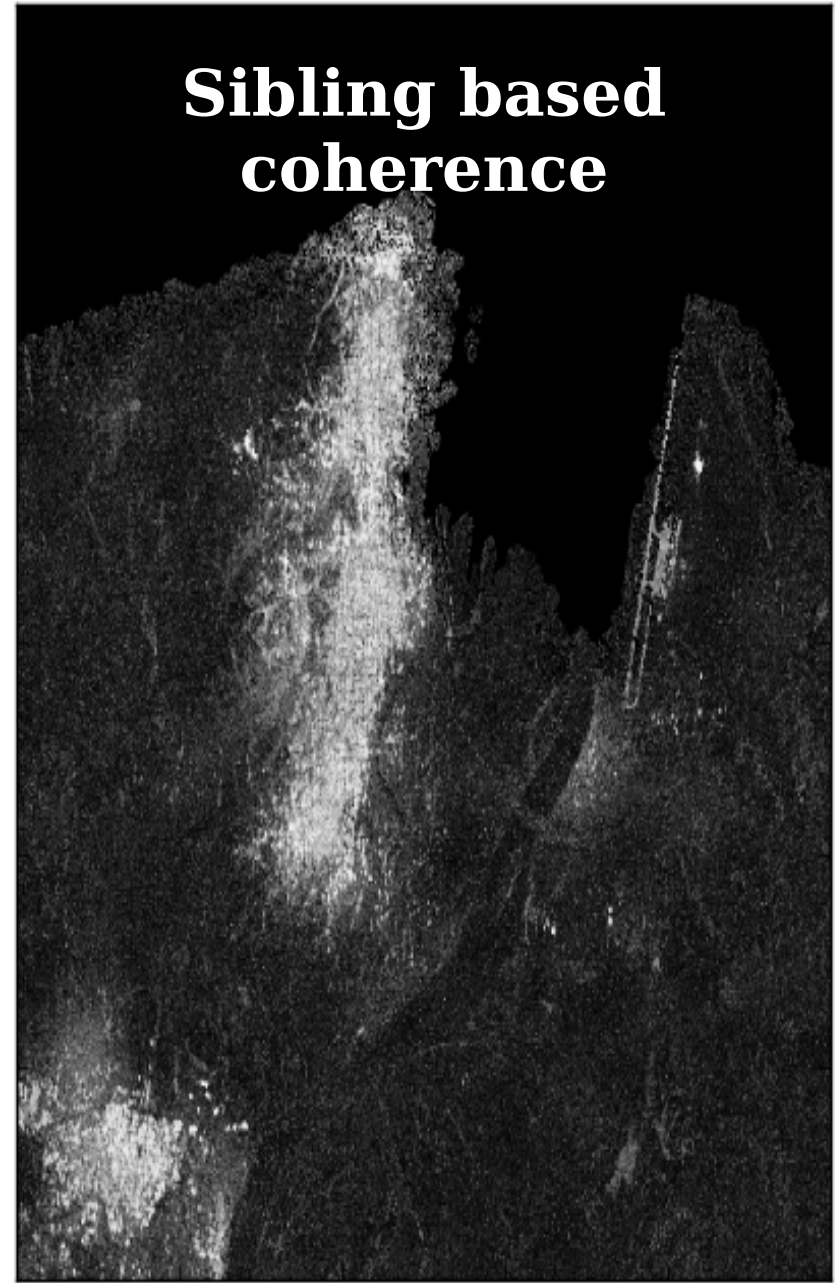


Coherence comparison

**Boxcar 7x7
window**

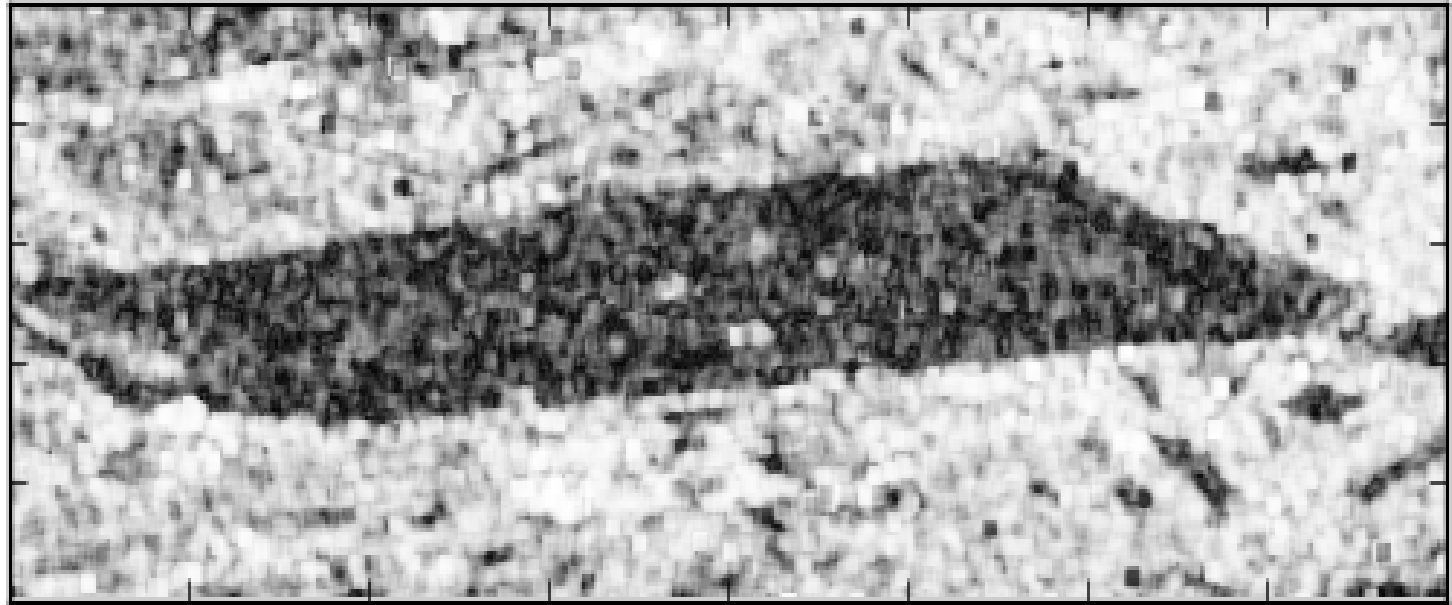


**Sibling based
coherence**

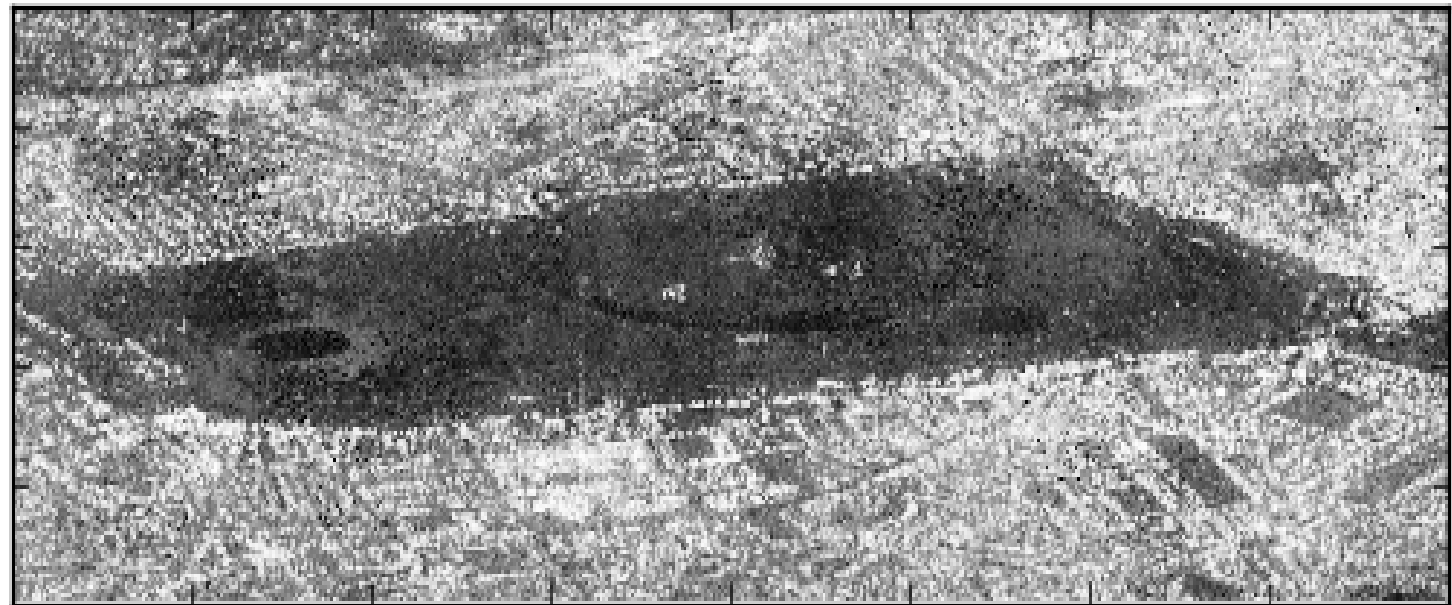


Coherence comparison

**Boxcar 7x7
window**

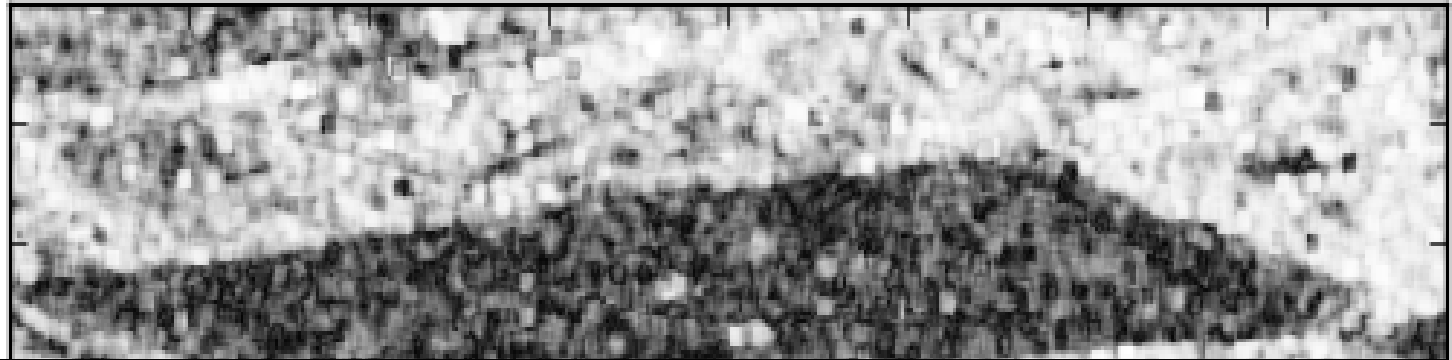


**Sibling based
coherence**



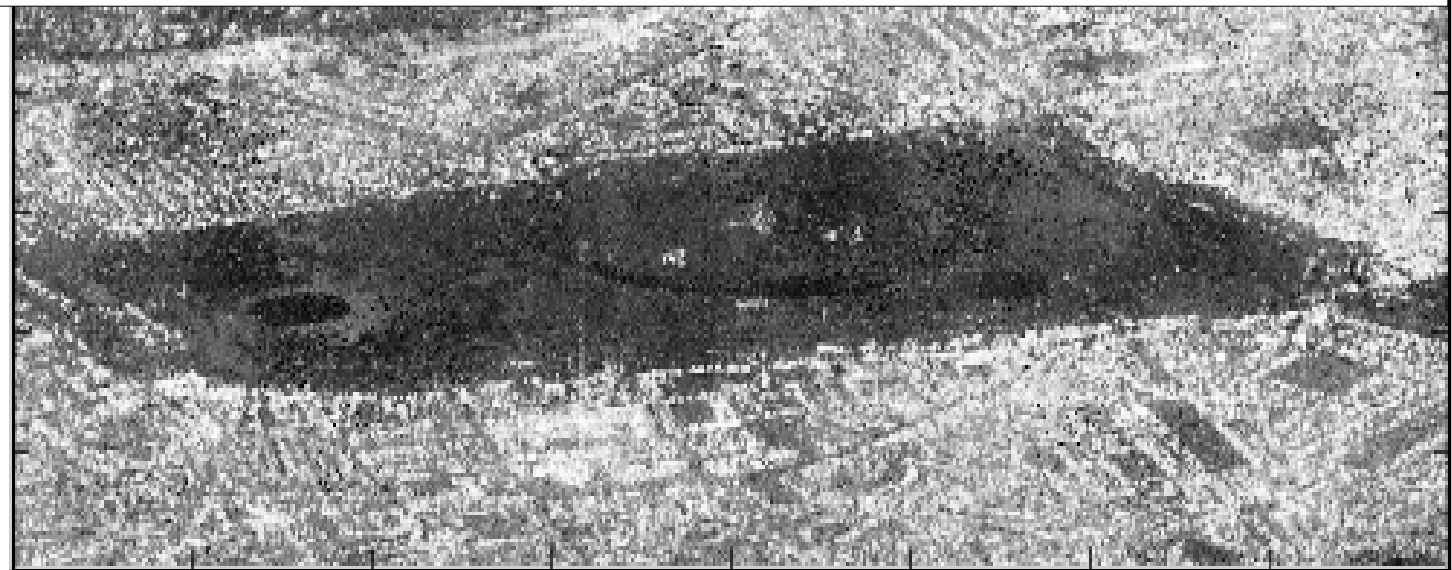
Coherence comparison

**Boxcar 7x7
window**



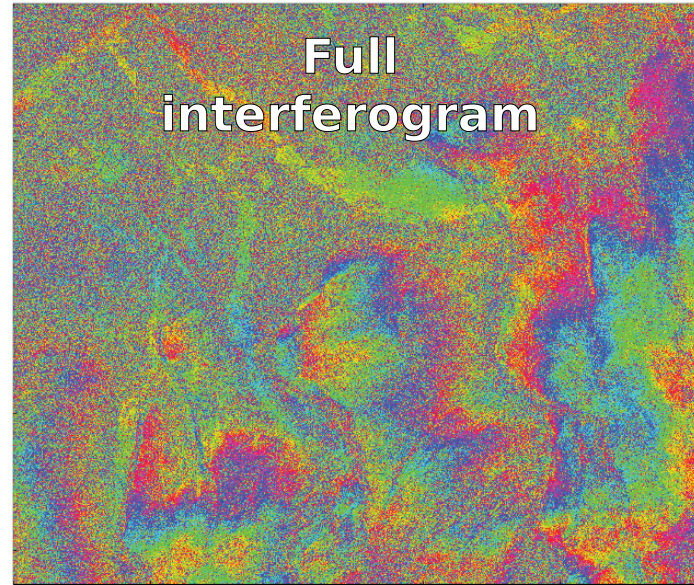
Using sibling based ensembles in coherence estimates result in high resolution, sharp coherence images.

**Sibling based
coherence**

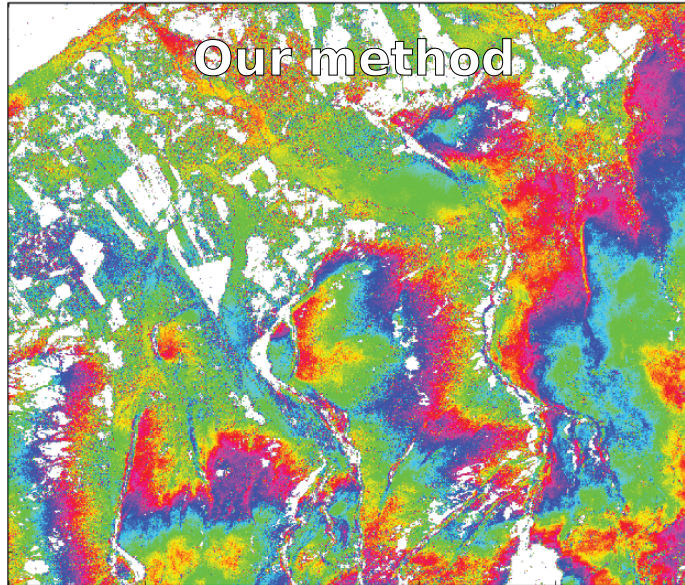


Point selection comparison

Full
interferogram



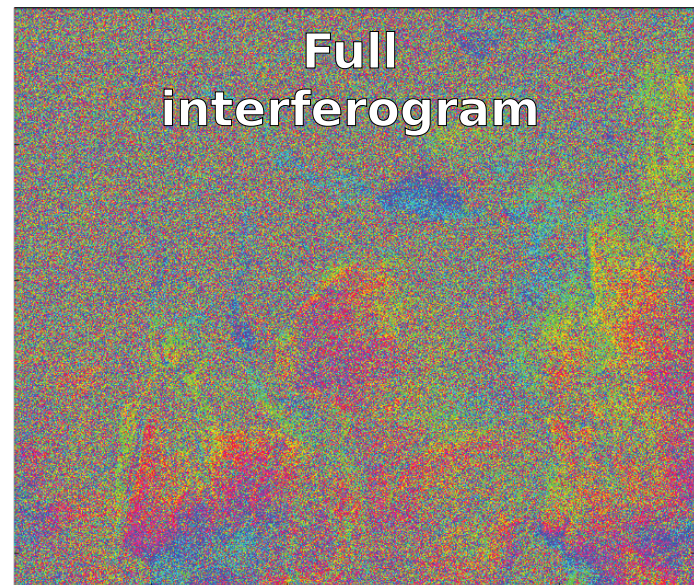
Our method



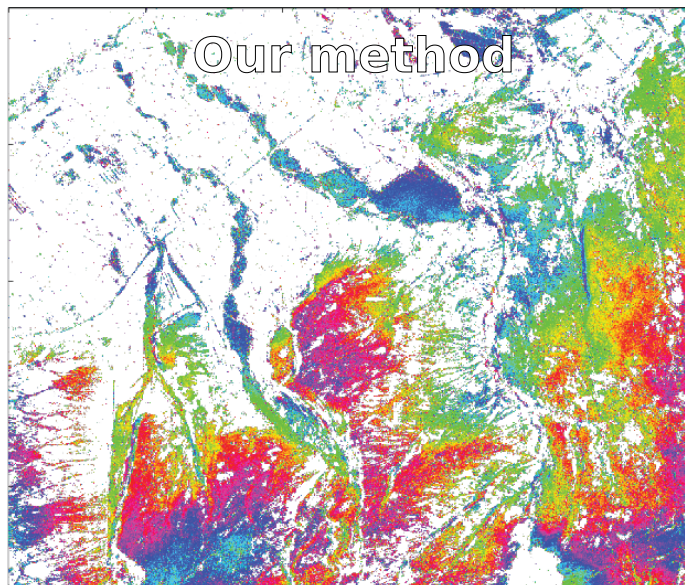
Small baseline



Full
interferogram



Our method



Small baseline



Point selection comparison

Full
interferogram

Our method

Small baseline

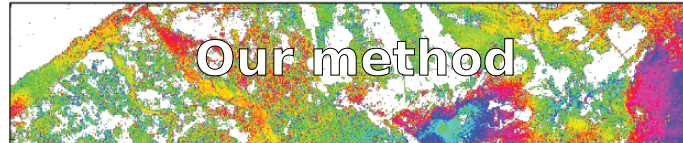
Full
interferogram

Our method

Small baseline

Point selection comparison

Full
interferogram



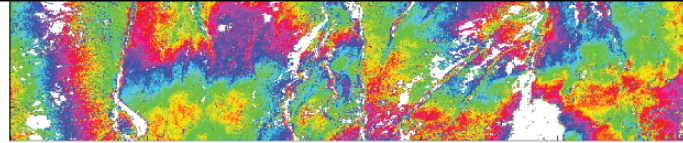
Our method



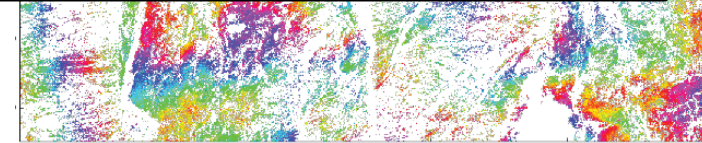
Small baseline

Small baseline (and PS) methods have to compromise between images with variable coherence, leading to significant loss in information.

Full
interferogram



Our method



Small baseline

Point selection comparison

Full
interferogram

Our method

Small baseline

Small baseline (and PS) methods have to compromise between images with variable coherence, leading to significant loss in information.

Full
interferogram

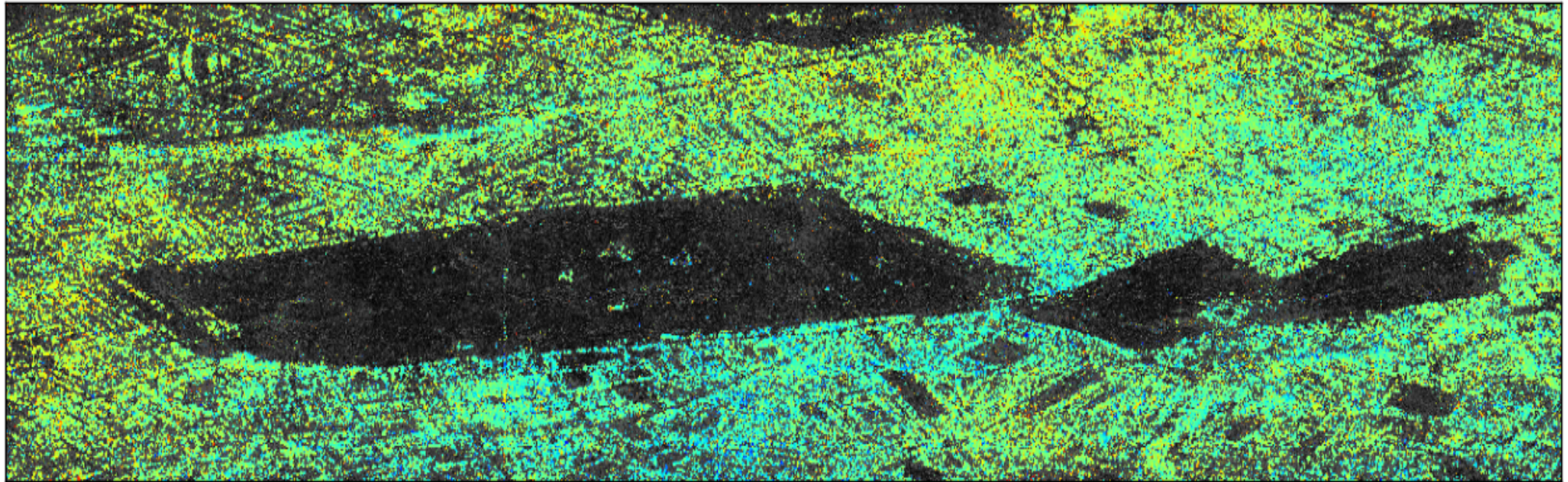
Our method

Small baseline

Point selection compromise in PS/SB methods does not just lead to loss of information, but also introduction of noise

Point selection

20150515-20150527



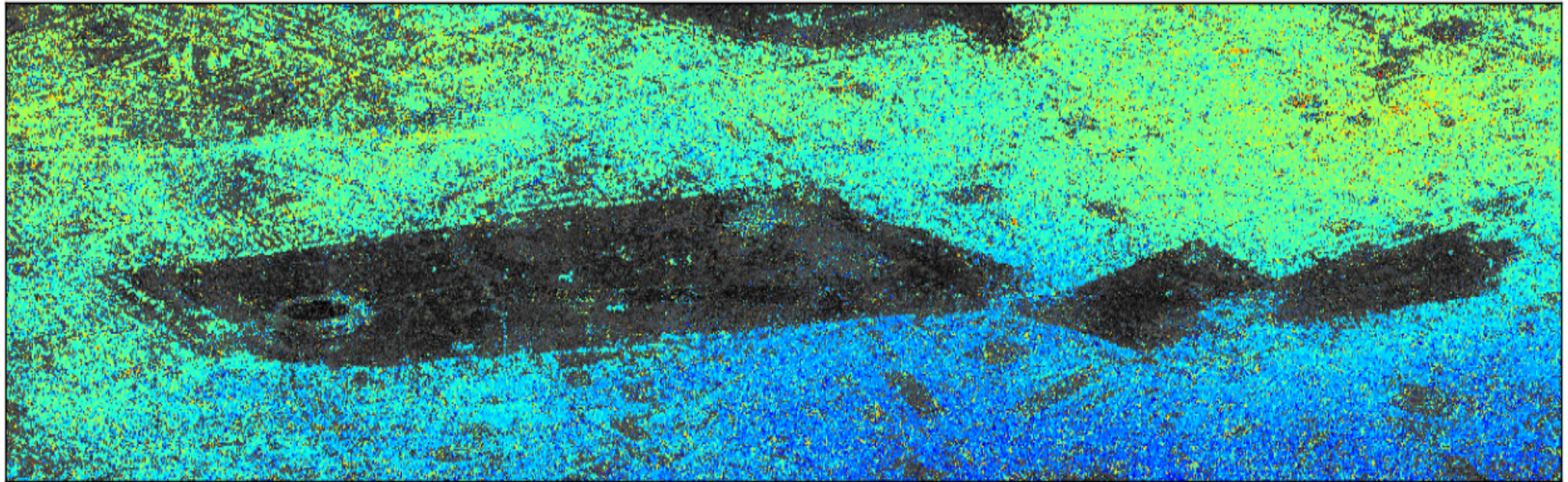
-
20

0
[m
m]

20

Variable point selection

20150714-20150726



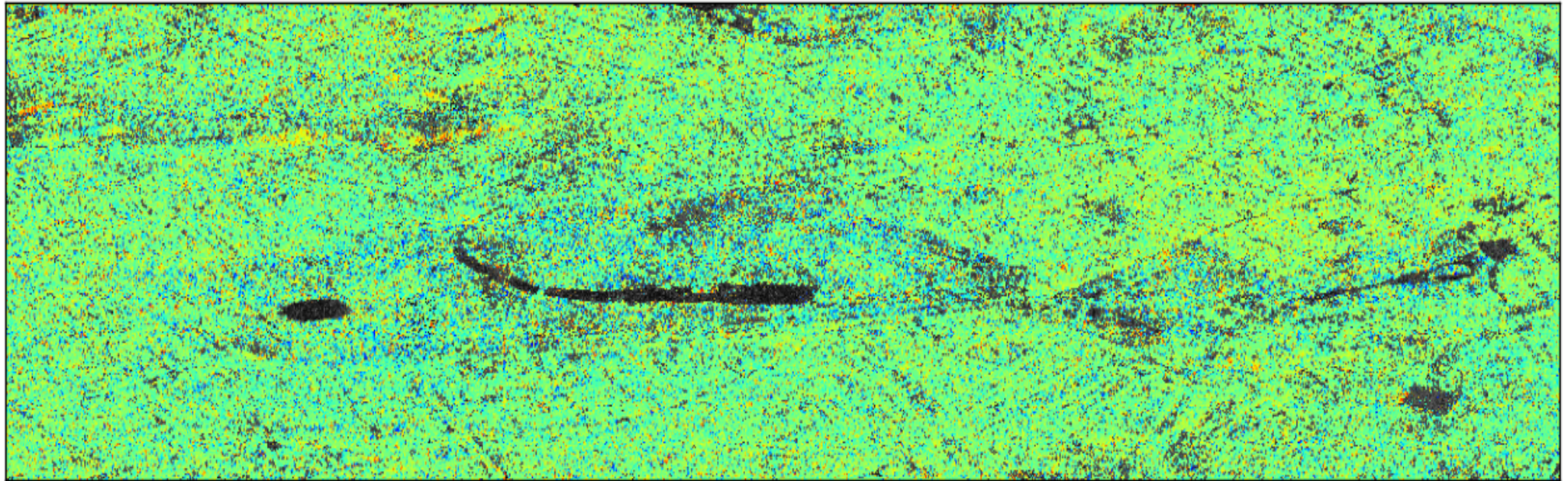
-
20

0
[m
m]

20

Variable point selection

20161129-20161205



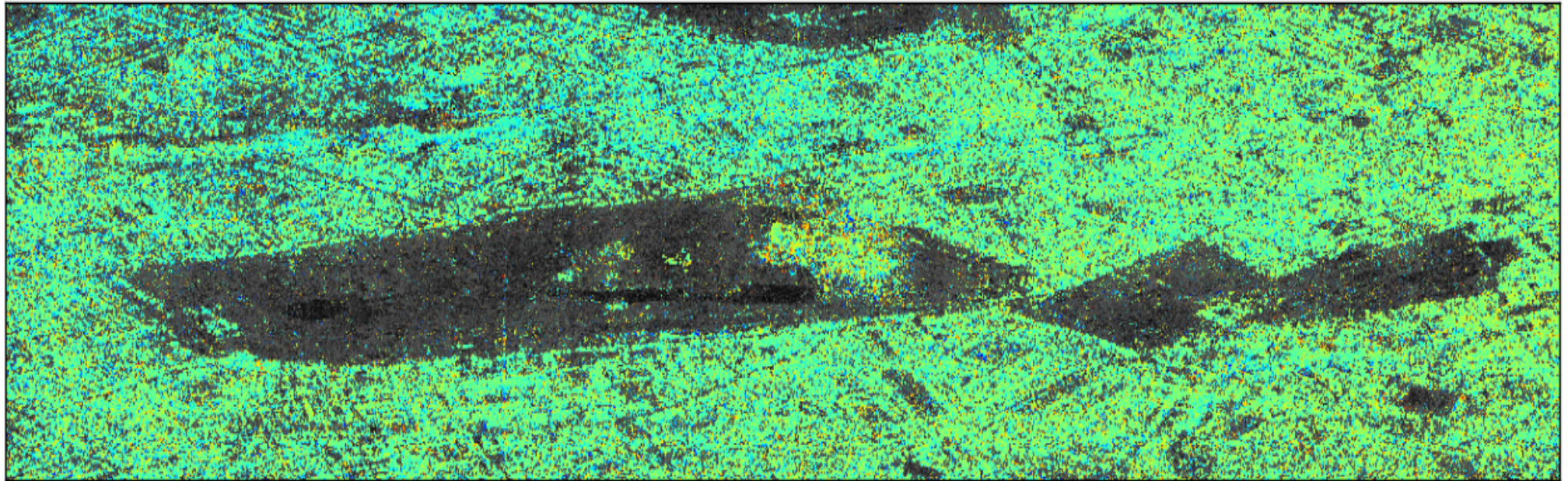
-
20

0
[m
m]

20

Variable point selection

20161205-20161211



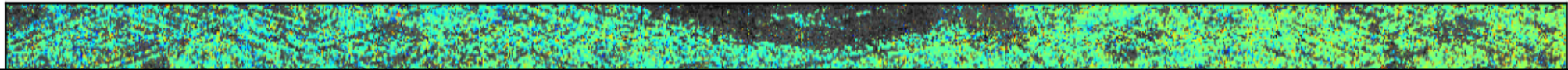
-
20

0
[m
m]

20

Variable point selection

20161205-20161211



Point selection on an interferogram-by-interferogram basis removes the selection compromise inherent in many time series techniques.

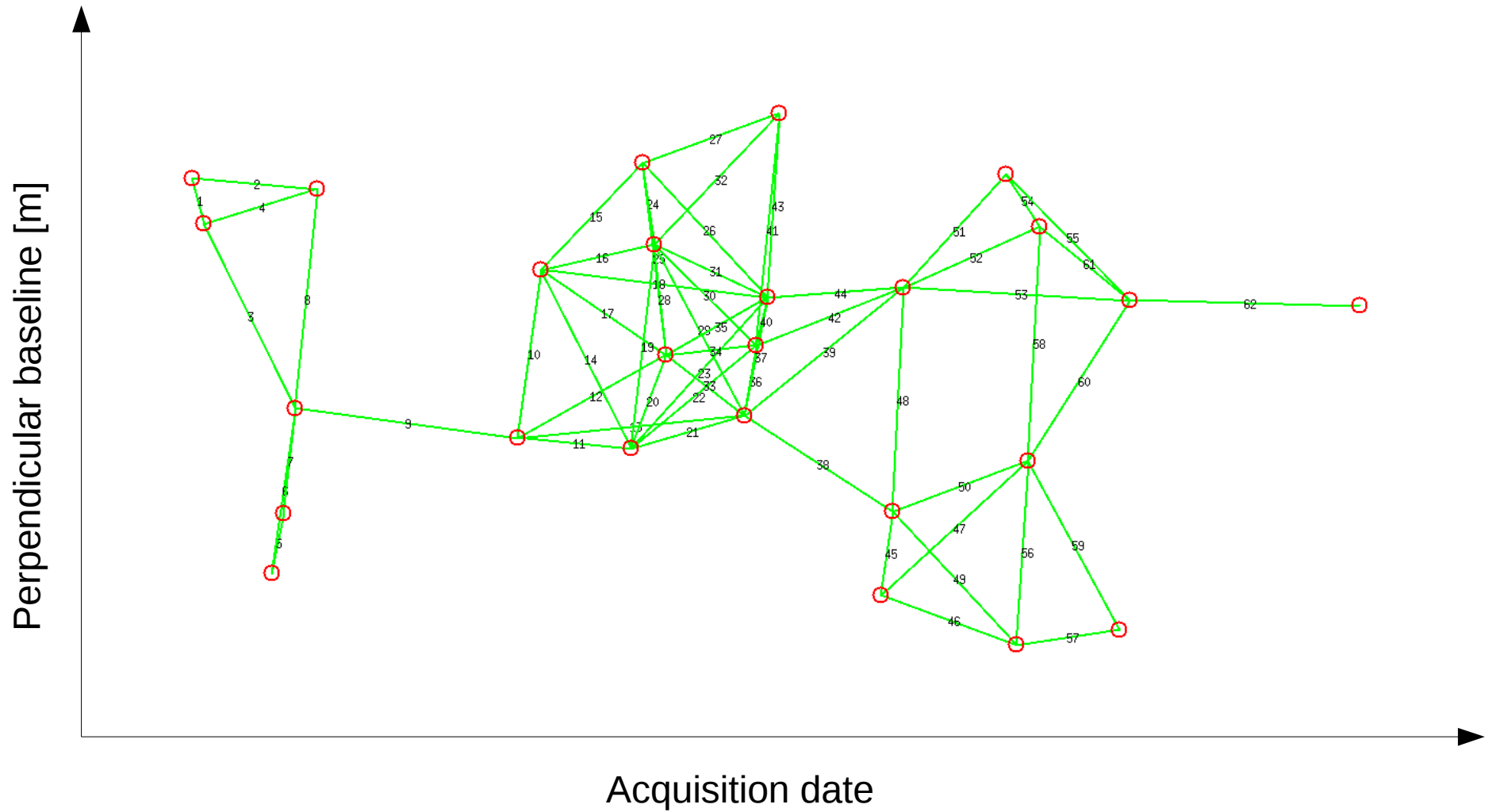


-
20

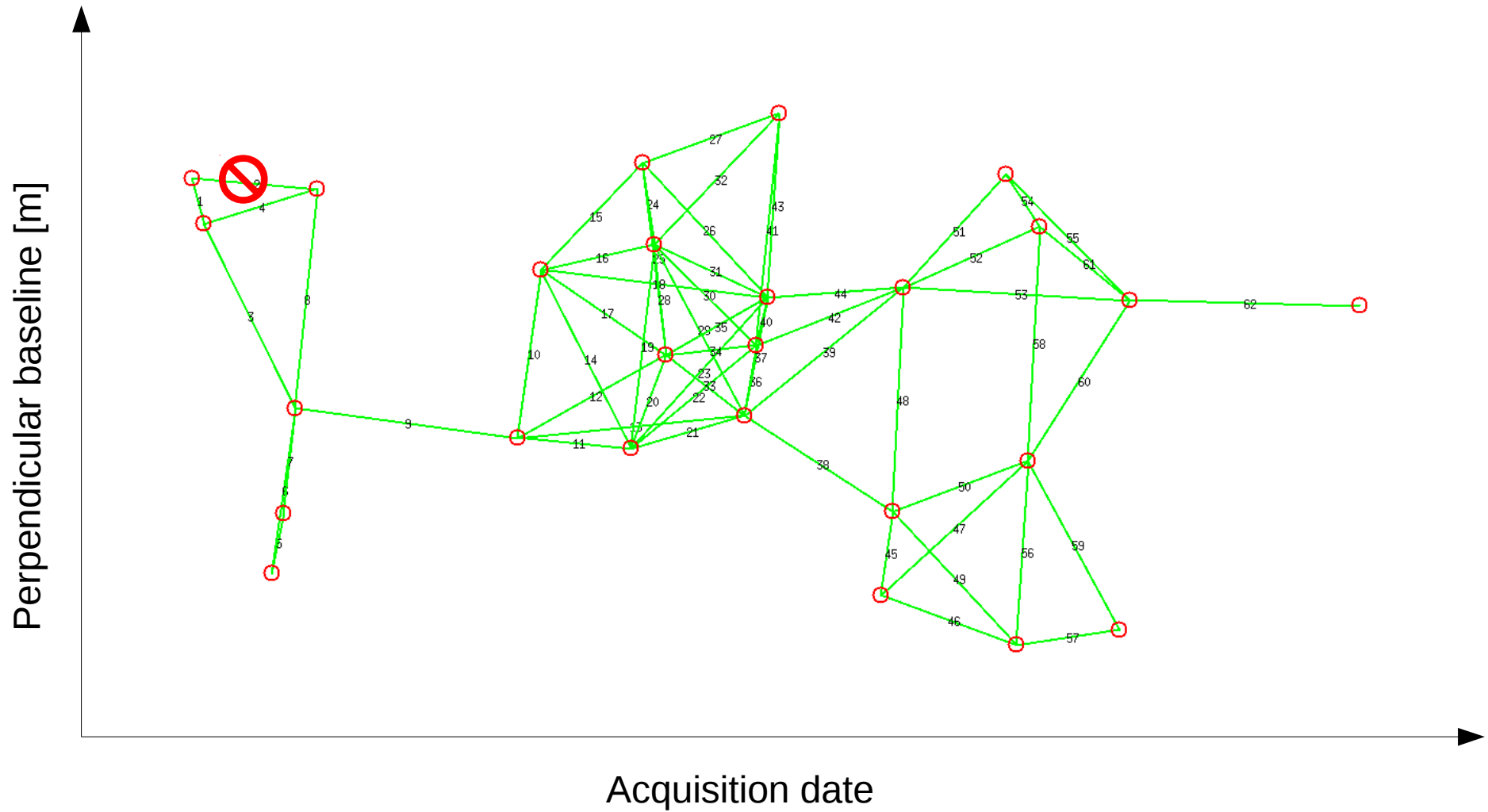
0
[m
m]

20

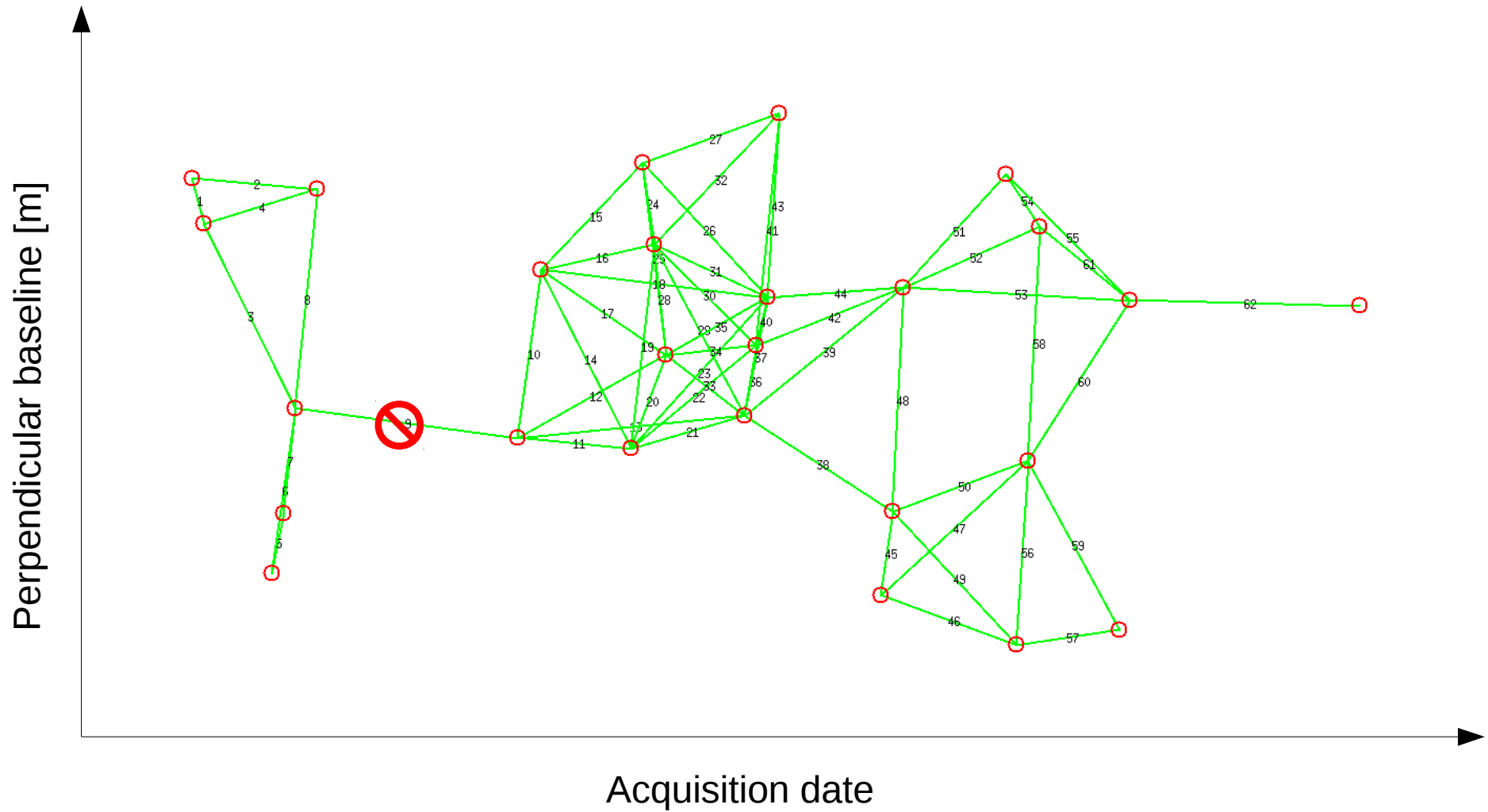
Timeseries inversion



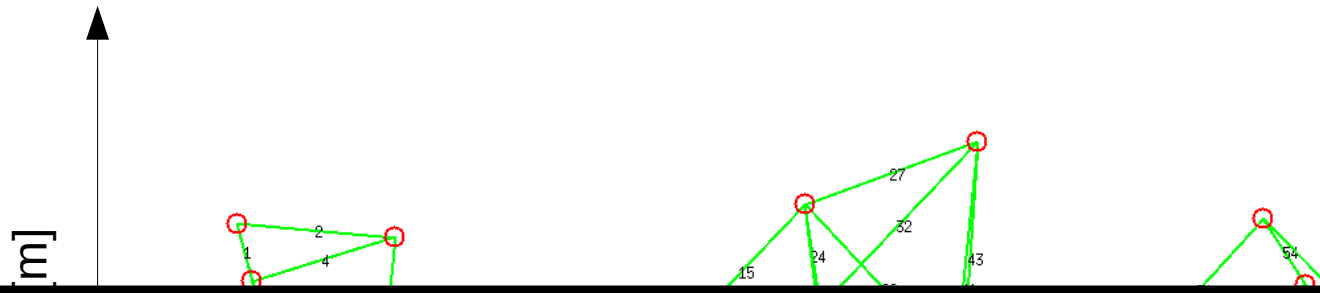
Timeseries inversion



Timeseries inversion



Timeseries inversion



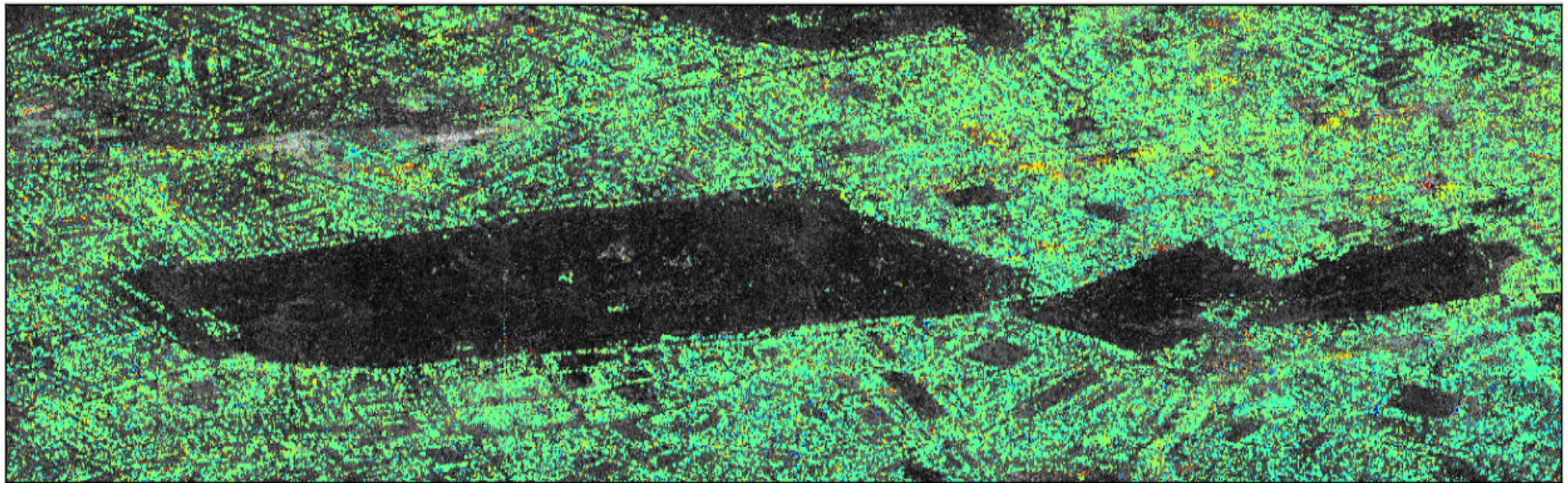
Variable point selection no longer guarantees fully connected network for inversion, complicating velocity estimation, unwrapping, atmosphere estimation, and many other operations in the time domain.

Acquisition date

Timeseries inversion

Linear velocity estimate

(only points for which there is a fully connected SB network)



-20

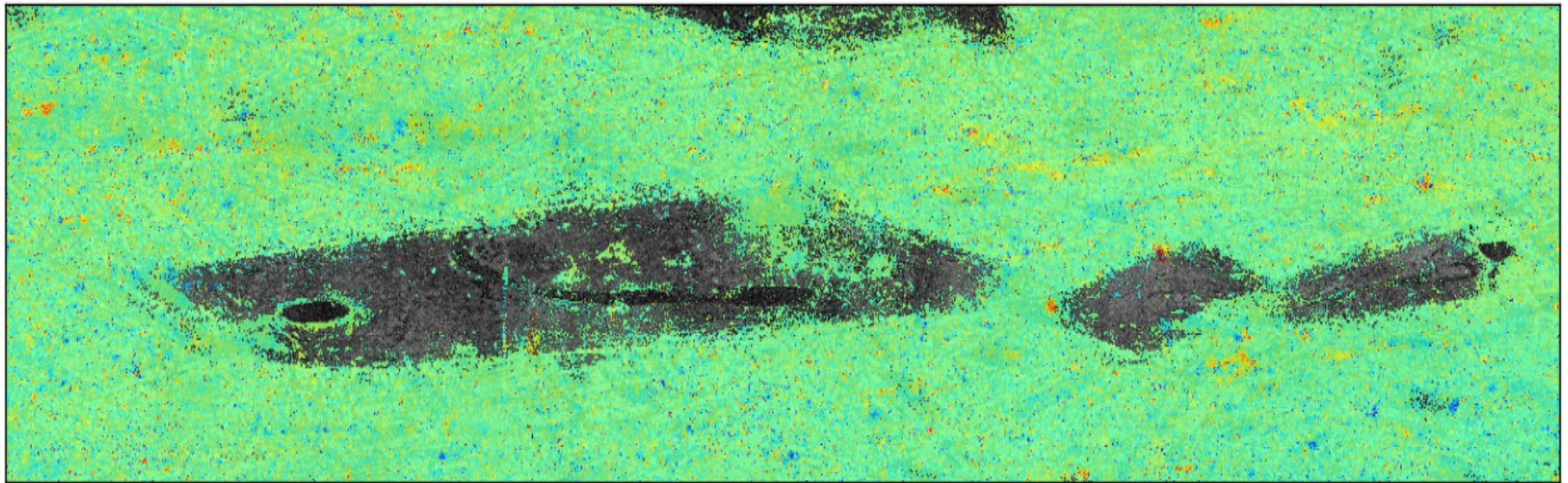
0

20

[mm/yr]

Timeseries inversion

**Linear velocity estimate
(Points present in at least 15 epochs)**

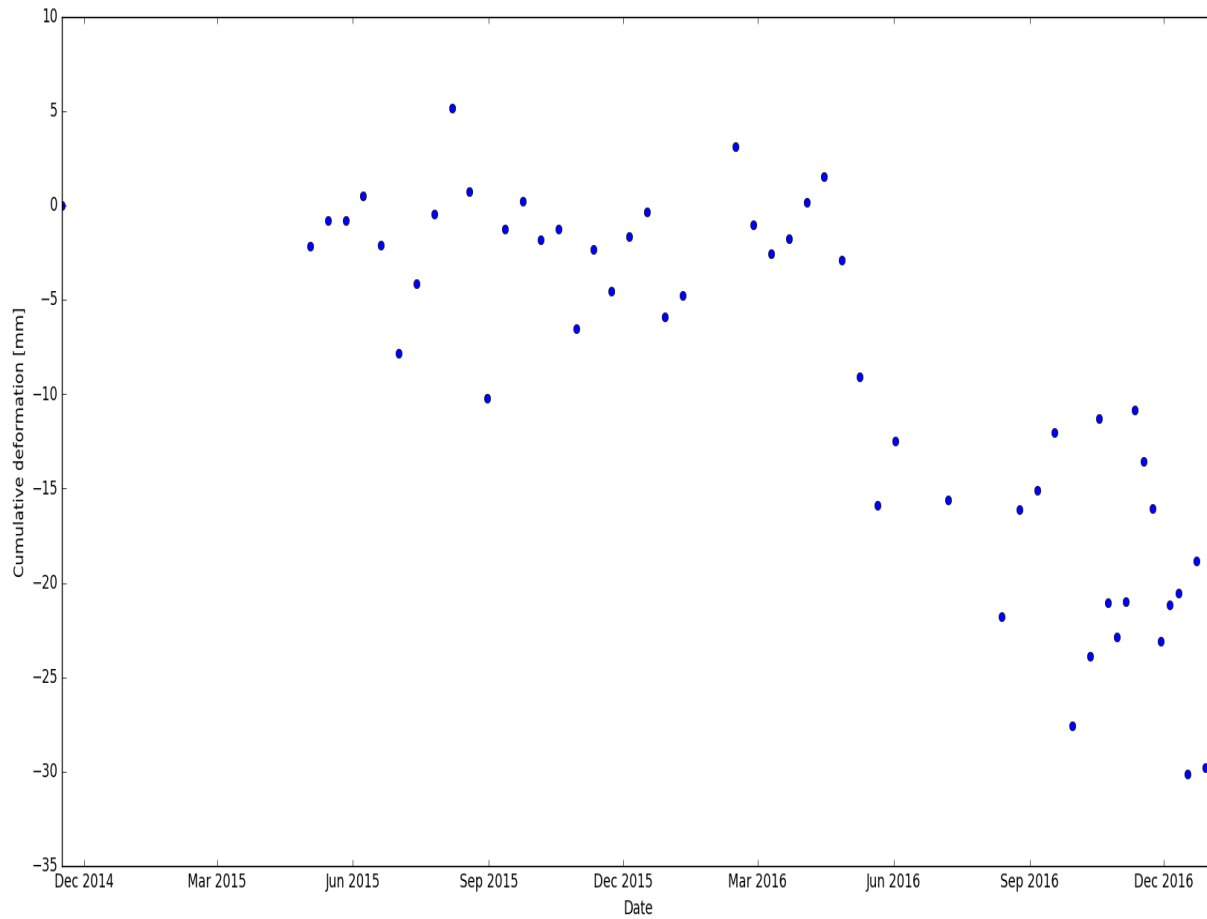


-20

0
[mm/yr]

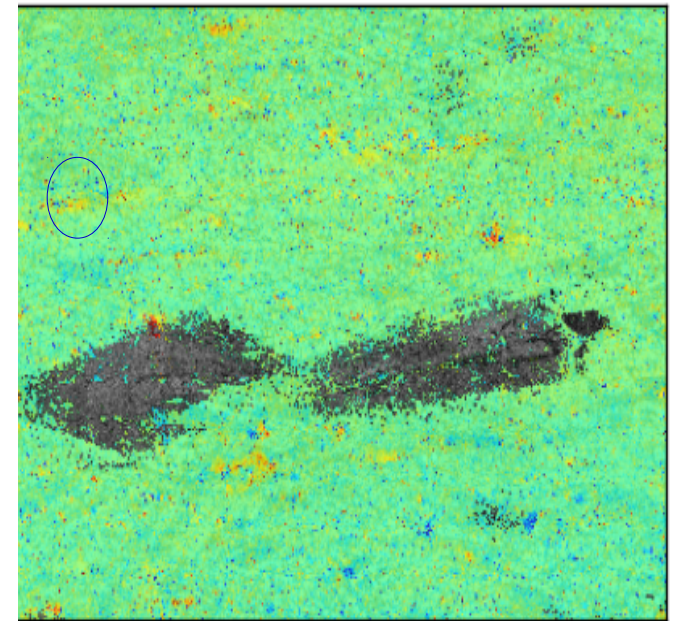
20

Timeseries inversion



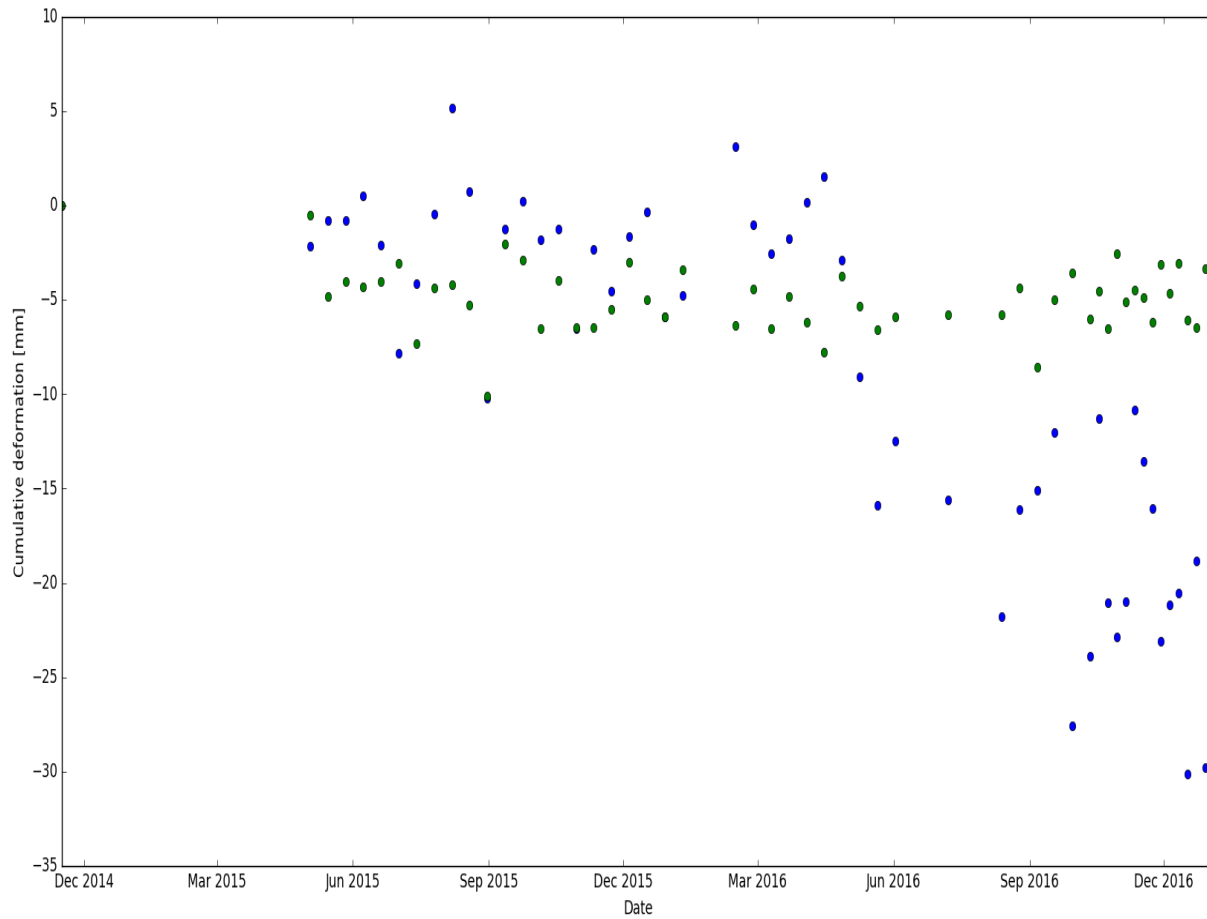
[mm/yr]

ite



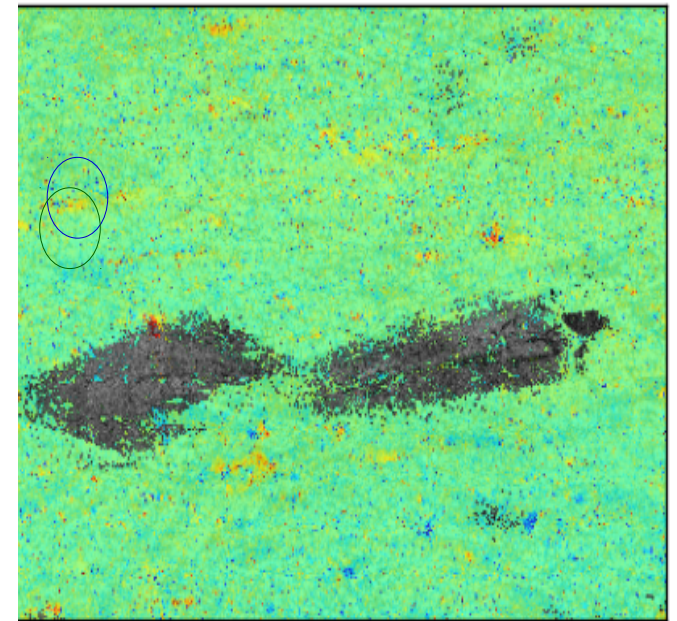
20

Timeseries inversion



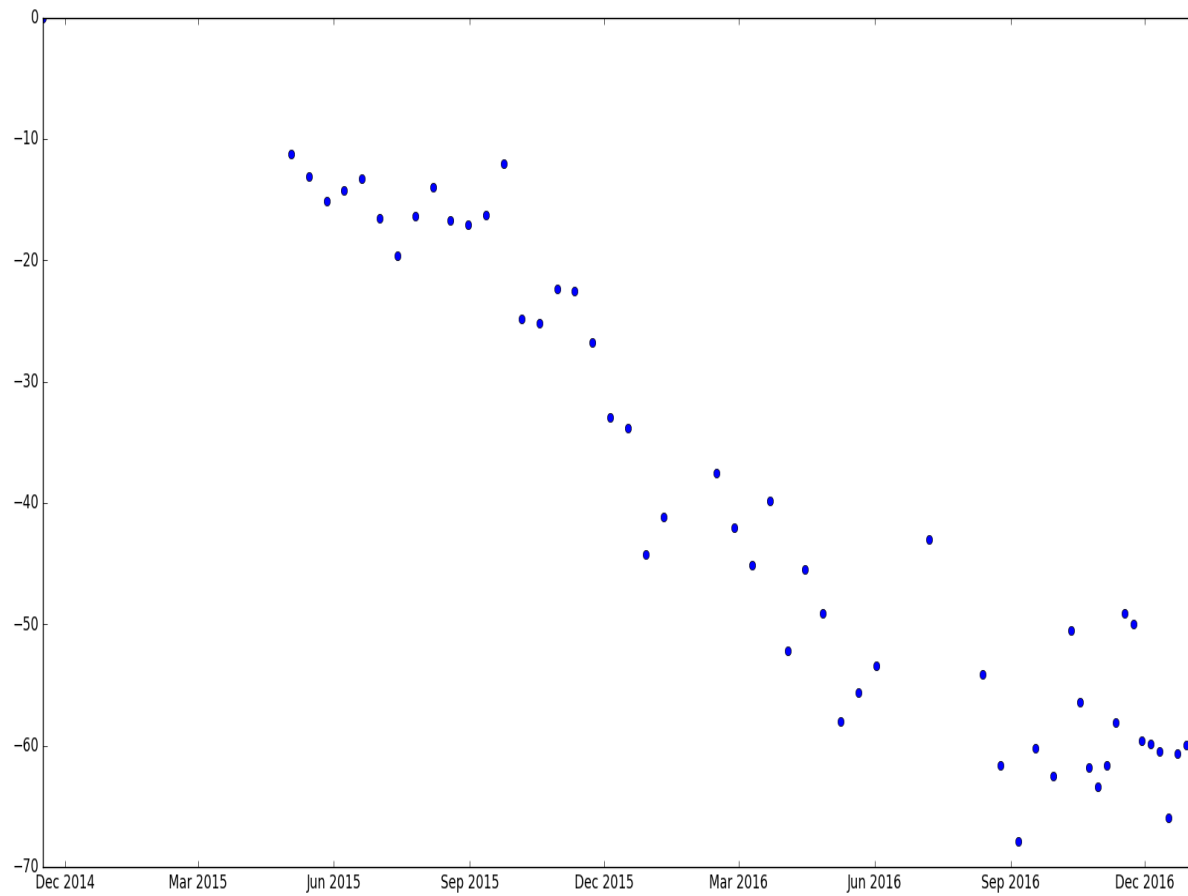
[mm/yr]

ite



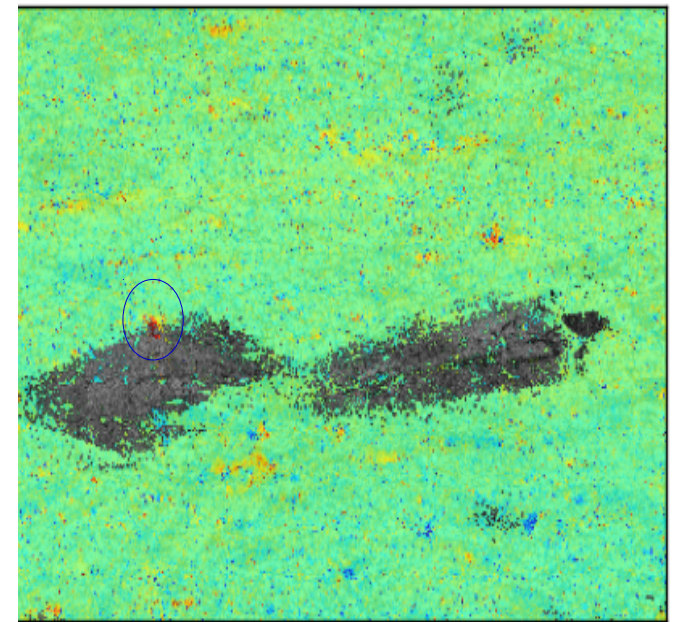
20

Timeseries inversion



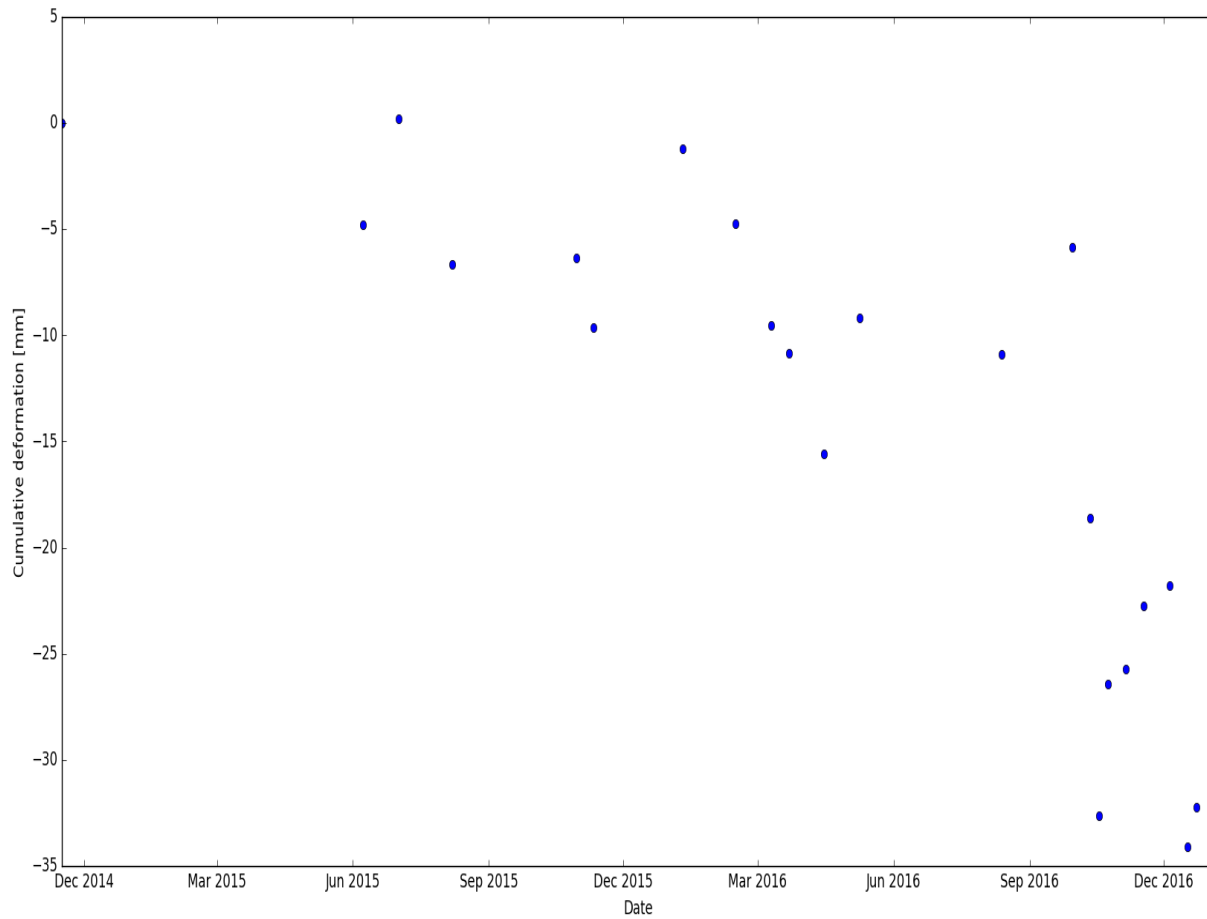
[mm/yr]

ite



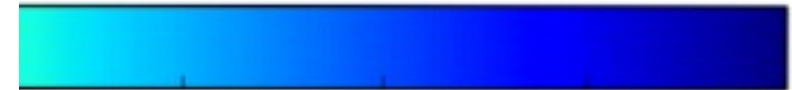
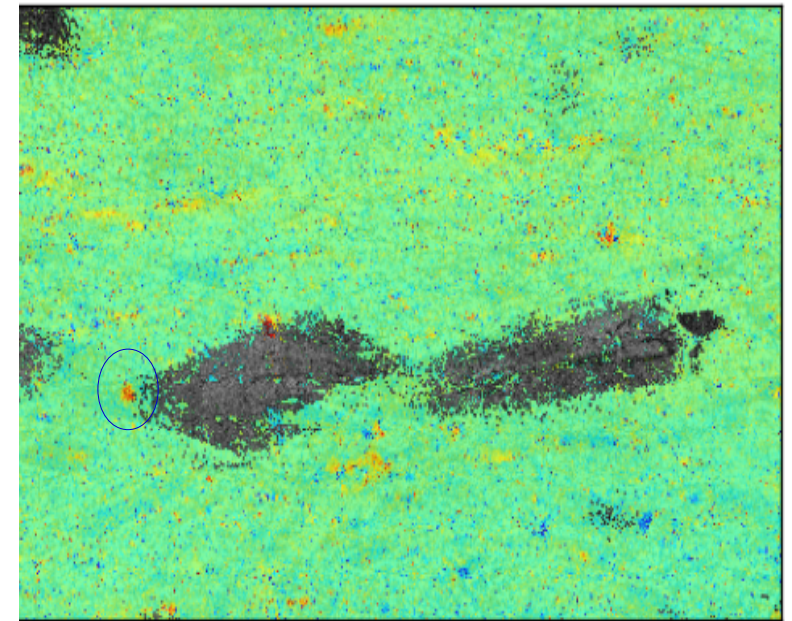
20

Timeseries inversion



[mm/yr]

imate



20

Take home messages

- Effective monitoring requires efficient processing methods
- Sibling based ensembles result in high resolution, sharp coherence images
- Individual point selection avoids the selection compromise inherent in many time series methods
- Variable point selection complicates operations in time, like unwrapping and certain atmospheric corrections.



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