

# RAF Technical Note: Processing Algorithms

Variables and Algorithms Used to Produce Data Products from Research Aircraft

revision of 2012

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# 1 INTRODUCTION

## 1.1 Background Information

This technical report defines the variables used in data sets that are collected by the research aircraft operated by the Research Aviation Facility (RAF) of the National Center for Atmospheric Research. Where appropriate, it also documents the equations that are used by the processing software (currently “nimbus”) to calculate the derived measurements that result from the use of one or more other basic measurements (e.g., potential temperature). Since 1993, data from research flights have been archived in NetCDF format (cf. <http://www.unidata.ucar.edu/software/netcdf/docs/>), and the NetCDF header for recent projects includes detailed information on the measurements present in the file, how they depend on other measurements, units, etc.

Currently, the data acquisition process on the research aircraft of the Research Aviation Facility, Earth Observing Laboratory, proceeds as follows:

1. Analog or digital outputs from instruments are sampled at regular intervals, typically 50 Hz when possible. Analog outputs are converted to digital values via analog-to-digital converters. The investigator’s handbooks for each aircraft describe this process in detail, including resolution of the sampling and handling of the results. Often, signals from user-supplied instruments are also included in the measured values that are handled by the data system.
2. The digital outputs are then recorded by the data system on the aircraft. Currently, this is a task of the “NIDAS” system described below. That system also controls the sampling, time stamps, and other aspects of data recording.
3. In flight, the data are processed by the “nimbus” data processing program, which makes them available for display via “aeros” for real-time monitoring of measurements.
4. Following the flight, *nimbus* again processes the data. At this stage, measurements can be re-sampled with averaging and/or interpolation to produce different time frequencies, and known lags in measurements can be introduced to adjust measurements to a common time basis. As part of this processing, *nimbus* applies calibration coefficients where appropriate to convert recorded values (e.g., voltage) to engineering units (e.g., °C). Determining or checking these calibration coefficients is part of the pre-flight and post-flight procedures for each project.
5. The output from *nimbus* is the data file that is the permanent archive from the experiment, often after merging in additional data sets from users that are not recorded in the original data file produced by NIDAS. These files, in NetCDF format, have headers that contain metadata on each measurement (such as the calibration coefficients, the instrument that produced the measurement, etc.). Many of the variables in these files are discussed in this technical note, but the files may also include additional project-specific measurements for which the NetCDF header and the project reports will be the only documentation.

The data system has changed several times over the history of RAF. For a discussion of the history of the data systems, see [ADShistory.pdf](#), written by Richard Friesen. The versions of data systems that produced most of the data still available were, approximately, as given in the following table:

<b>Data System</b>	<b>start</b>	<b>end</b>	<b>Aircraft</b>
ADS I	1984	1992	King Air 200T, Sabreliner (1987), Electra (1991)
ADS II	1992	2007	C-130
ADS III (NIDAS) <sup>a</sup>	2005		GV, C-130 (2007)

<sup>a</sup>ADS III is the name given to the full data system, which includes these components: NIDAS (for data acquisition and recording); NIMBUS (for data processing, both in flight and after the flight); AEROS (for data display in flight); and the Mission Coordinator Station and satellite communications system (for transmission of data to and from the aircraft, display of such data for mission decisions, and support for written “chat” communications among project participants both on the aircraft and on the ground).

Before 1993, data were processed by a different program, “GENPRO,” and a different output format (also named GENPRO) was used for archived datasets. Appendix E in RAF Bulletin 9, the previous description of RAF data products that is now superseded by this technical note, describes that format. Some variable names in this document, esp. in section 11, refer to obsolete variable names, some used with GENPRO and others referring to instruments that are now retired. These names are included here so that this report can be a reference for older archived data as well as for current data files.

## 1.2 Alphabetical List of Variables

At the end of this section, on page on this page, there is a list of all the variable names that appear in standard data files along with links to the primary discussion of those variables. The index to this technical report ( on page 76) also includes all variables described here, and also some variables not discussed in detail in this document. Where possible, reference to those variables and information on the project(s) where they were used have been included also. In cases with multiple references, the bold entry is the primary discussion of the variable.

In some cases redundant measurements are present, often for key measurements like pressure or temperature. When these are used in subsequent calculation of derived variables like potential temperature, some choice is usually made regarding which measurement is considered most reliable for a particular project or flight, and a single derived variable is calculated on the basis of the chosen input variable(s). To record which measurements were so designated, a reference measurement chosen from a group of redundant measurements usually has a variable name ending with the letter(s) X or XC.<sup>1</sup>

<sup>1</sup>Some that do not follow this convention are ATTACK, SSLIP and EDPC; see the individual descriptions that follow.

## Variable Names

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ACDP, 54  
ACINS, 19  
ADIFR, 47  
AF300, 54  
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AFSSP, 54  
AKFXx (obsolete), 73  
AKRD, 47  
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ATRF (obsolete), 74  
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 GGNSAT, 23  
 GGQUAL, 24  
 GGSPD, 23  
 GGSTATUS, 24  
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 PLWCF, 56  
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 PSURF, 45  
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XICN, 64

XICNC, 64

XUVI, 39, 44

XUVP, 44

XUVT, 44

XVI (obsolete), 72

YVI (obsolete), 72

### 1.3 Constants Used in Data Processing

The following box contains values used for some constants in this document. For reference, the symbols used here also appear at the start of the index along with their meanings and links to where they are defined. Where references are to the “NIST Chemistry WebBook”, the associated URL is <http://webbook.nist.gov>. References to the CODATA Internationally recommended values of the Fundamental Physical Constants are available at <http://physics.nist.gov/cuu/Constants>. The optimization involved in adjustment of these coefficients is documented in Mohr et al., 2008a and 2008b, referenced at that URL.<sup>2</sup>

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<sup>2</sup>P. J. Mohr, B. N. Taylor, and D. B. Newell, Rev. Mod. Phys 80(2), 633-730(2008); P. J. Mohr, B. N. Taylor, and D. B. Newell, J. Phys. Chem. Ref. Data 37(3), 1187-1284(2008).

**Table of Constants**

$g$  = acceleration of gravity<sup>a</sup> at latitude  $\lambda$  and altitude  $z$  above the WRS-80 geoid,<sup>b</sup>

$$g_{\lambda} = g_e \left( \frac{1 + g_1 \sin^2(\lambda)}{(1 - g_2 \sin^2 \lambda)^{1/2}} \right) - a_z z \quad (1)$$

where  $g_e = 9.780327 \text{ m s}^{-2}$  is the reference value at the surface and equator,

$g_1 = 0.001931851$ ,  $g_2 = 0.006694380$ , and  $a_z = 3.086 \times 10^{-6} \text{ m}^{-1}$ .

$T_0$  = temperature in kelvin corresponding to  $0^\circ\text{C} = 273.15 \text{ K}$

$T_3$  = temperature corresponding to the triple point of water =  $273.16 \text{ K}$

$M_a$  = molecular weight of dry air<sup>a</sup>,  $28.9637 \text{ kg kmol}^{-1}$  <sup>c</sup>

$M_w$  = molecular weight of water,  $18.0153 \text{ kg kmol}^{-1}$  <sup>d</sup>

$R_0$  = universal gas constant<sup>a</sup> =  $8.314472 \times 10^3 \text{ J kmol}^{-1} \text{ K}^{-1}$  <sup>e</sup>

$R_d = (R_0/M_d)$  = gas constant for dry air

$R_w = (R_0/M_w)$  = gas constant for water vapor

$R_E$  = radius of the Earth =  $6.371229 \times 10^6 \text{ m}$  <sup>f</sup>

$c_p$  = specific heat of dry air at constant pressure =  $\frac{7}{2}R_d = 1.00473 \times 10^3 \text{ J kg}^{-1} \text{ K}^{-1}$  <sup>g</sup>

(value at  $0^\circ\text{C}$ ; small variations with temperature are not included here)

$c_v$  = specific heat at constant volume =  $\frac{5}{2}R_d = 0.71766 \times 10^3 \text{ J kg}^{-1} \text{ K}^{-1}$

(value at  $0^\circ\text{C}$ ; small variations with temperature are not included here)

$\gamma$  = ratio of specific heats,  $c_p/c_v$ , taken to be 1.4 (dimensionless) for dry air

$\Omega$  = angular rotation rate of the Earth =  $7.292115 \times 10^{-5} \text{ radians/s}$

$\Omega_{Sch}$  = angular frequency of the Schuler oscillation =  $\sqrt{\frac{g}{R_E}}$

$\sigma$  = Stephan-Boltzmann Constant =  $5.6704 \times 10^{-8} \text{ W m}^{-2} \text{ K}^{-4}$  <sup>h</sup>

<sup>a</sup>In the International Standard Atmosphere  $g$  is specified as  $9.80665 \text{ m s}^{-2}$ ,  $M_w = 28.9644$ , and  $R_0 = 8.31432 \times 10^3 \text{ J kmol}^{-1} \text{ K}^{-1}$

<sup>b</sup>cf., e.g., Moritz, H., 1988: Geodetic Reference System 1980, Bulletin Geodesique, Vol. 62, no. 3.

<sup>c</sup>Jones, F. E., 1978: J. Res. Natl. Bur. Stand., 83(5), 419, as quoted by Lemmon, E. W., R. T. Jacobsen, S. G. Penoncello, and D. G., Friend, J. Phys. Chem. Ref. Data, Vol. 29, No. 3, 2000, pp. 331-385. The quoted values of mole fraction from Jones (1978) and the calculation of mean molecular weight are tabulated below using values of molecular weights taken from the NIST Standard Reference Database 69: NIST Chemistry WebBook as of March 2011. With  $\text{CO}_2$  increased to about 0.00039 and others decreased proportionately, the mean is 28.9637.

Gas	mole fraction $x$	molecular weight $M$	$x * M$
$\text{N}_2$	0.78102	28.01340	21.87903
$\text{O}_2$	0.20946	31.99880	6.70247
Ar	0.00916	39.94800	0.36592
$\text{CO}_2$	0.00033	44.00950	0.01452
Mean:			28.96194

<sup>d</sup>NIST Standard Reference Database 69: NIST Chemistry WebBook as of March 2011

<sup>e</sup>2006 CODATA

<sup>f</sup>matching the value used by the inertial reference systems discussed in Section 3

<sup>g</sup>The specific heat of dry air at 1013 hPa and 250–280 K as given by Lemmon et al. (2000) is  $29.13 \text{ J/(mol-K)}$ , which translates to  $1005.8 \pm 0.3 \text{ J/(kg-K)}$ . However, the uncertainty limit associated with values of specific heat is quoted as 1%, and the experimental data cited in that paper show scatter that is at least comparable to several tenths percent, so the ideal-gas value cited here is well within the range of uncertainty. For this reason, and because this value is in widespread use, the ideal-gas value is used throughout the algorithms described here.

<sup>h</sup>2006 CODATA

# List of Symbols

$\alpha$ = recovery factor, temperature probe, 32	$\lambda$ = tropospheric lapse rate, standard atmosphere, 26
$\alpha = \tanh(e_s(T - T_x))$ , Murphy/Koop equations, 36	$\lambda$ = latitude, 11
$\chi$ = liquid water content, 52	$\lambda_c$ = thermal conductivity, dry air, 52
conversion factor, kg to g, 39	$L_V$ = latent heat of vaporization of water, 52
$C_{kg2g}$ = conversion factor, g to kg, 52	$M$ = Mach number, ratio of airspeed to the speed of sound, 33
$C_{mb2Pa}$ = conversion factor, mb to Pa, 39	$M_d$ = molecular weight of dry air, 11
$c_p$ = specific heat of dry air at constant pressure, 11	$\mu_a$ = dynamic viscosity of air, 52
$C_{rd}$ = conversion factor, radians to degrees ( $180/\pi$ ), 49	$M_w$ = molecular weight of water, 11
$c_v$ = specific heat of dry air at constant volume, 11	$Nu$ = Nusselt number, 52
$c_w$ = specific heat of liquid water, 52	$\Omega$ = angular rotation rate of the Earth, 11
$Cy_i$ = concentration from hydrometeor probe y in channel i, 55	$\Omega_{Sch}$ = angular frequency of the Schuler oscillation, 11
$d_{e,i}$ = equivalent melted diameter for channel i of a hydrometeor spectrometer, 56	$p$ = pressure, 33
$d_i$ = diameter of hydrometeor in channel i, 55	$p_0$ = reference pressure equal to 1000 mb, 41
$e$ = water vapor pressure, 36	$p_a$ = reference pressure for zero altitude, ISA, 26
$e_a$ = ambient water vapor pressure, 36	$p_a$ = ambient air pressure, 34
$e_h$ = water vapor pressure in an instrument housing, 37	$p_d$ = partial pressure of dry air, 41
$e_{s,i}$ = equilibrium vapor pressure over a plane ice surface, 36	$p_h$ = pressure in a sensor housing, 37
$e_{s,l}$ = equilibrium vapor pressure over a plane water surface, 36	$p_T$ = pressure at the ISA tropopause, 26
$\eta$ =update constant for exponential updating, 29	$R_0$ = universal gas constant, 11
$f_c$ = cutoff frequency fo the filter $F_L$ , 28	$r$ = mixing ratio of water vapor, 41
$F_d$ = interpolation formula, dew point temperature from water vapor pressure, 37	$R_d$ = gas constant for dry air, 11
$F_L$ = digital low-pass filter, 28	$R_E$ = radius of the Earth, 11
$f(p, T_p)$ = enhancement factor for equilibrium water vapor pressure, 36	$Re$ = Reynolds number, 52
$g$ = acceleration of gravity, 11	$\rho_a$ = density of air, 52
$\gamma$ = ratio of specific heats of air, $c_p/c_v$ , 11	$\rho_w$ = density of liquid water, 56
	$R_W$ = gas constant for water vapor, 11
	$\sigma$ = Stephan-Boltzmann constant, 11
	$T_0$ = 273.15 K, 36
	$T_0$ = 273.15 K, 11
	$T_3$ = 273.16 K, 11
	$T_a$ = ambient air temperature in absolute units; sometimes, $T_K$ , 33
	$T_b$ = boiling temperature of water, 52

$T_{DP}$ = temperature at the dew point, 36  
 $T_{FP}$ = temperature at the front point, 36  
 $T_K$ = absolute temperature (in kelvin), 38  
 $T_L$ = temperature  
    lifted condensation level, 41  
 $T_p$  =dew point temperature if above 0°C, frost  
    point temperature otherwise, 36  
 $T_r$ = absolute reference temperature, STP, 64  
 $T_r$ = recovery temperature, 33  
 $T_T$ = temperature at the ISA tropopause, 26  
 $T_t$ = total air temperature, 33  
 $T_x$ = 218.8 k, Murphy/Koop equations, 36  
  
 $U_a$ = true airspeed (sometimes  $U$ ), 33  
 $U_s$ = speed of sound, 33  
  
 $V$ = volume, 33  
  
 $z$  = height, 11

## 2 GENERAL INFORMATION ABOUT DATA FILES

### 2.1 System of Units

This report will use the SI system of units, but with many exceptions. Among them are the following:

1. The millibar (mb), equal to one hectopascal (hPa), is sometimes used for pressure.
2. Many variables are presented in the units most often used for that variable, even when they involve CGS units or mixed CGS-MKS units, as for example  $[\text{g m}^{-3}]$  for liquid water content or  $[\text{cm}^{-3}]$  for droplet concentration.
3. Flow rates are often quoted in liters per minute (LPM) or standard liters per minute (SLPM) because those terms are linked to properties of commercially available instruments with flow control. One liter is  $10^{-3} \text{ m}^3$ . Because there is considerable ambiguity in the definition of “standard” conditions (regarding choice of the reference pressure and temperature), the particular usage will be documented when this term is used.
4. The International Bureau of Weights and Measures recommends against use of units like percent or parts per million, but these are in common use in atmospheric chemistry and elsewhere so data files continue to use those units for relative humidity or the concentration of chemical species. Typical units are ppmv or ppbv for parts per million by volume or parts per billion by volume. Care must be taken to interpret ppbv especially, because “billion” has different meaning in different languages and different countries; herein, 1 ppbv means a volumetric ratio of  $1:10^9$ . Many measurements produce native results in terms of a mass ratio, often described as a mixing ratio  $r_m$  in terms of mass of the measured gas per unit mass of “air” (where the weight of the “air” does not include the variable constituents, usually only significant for water vapor). The perfect gas law relates the density ratio of two gases ( $\rho_1 : \rho_2$ ) to the ratio of their partial pressures ( $p_1 : p_2$ ) or number densities ( $n_1 : n_2$ ), as follows:

$$r_m = \frac{\rho_1}{\rho_2} = \frac{p_1 M_1}{p_2 M_2} = \frac{n_1 M_1}{n_2 M_2}$$

where  $M_1$  and  $M_2$  are respective molecular weights for the two gases. The ratio of number densities or, equivalently, partial pressures, denoted here as  $r_v$  because it is also the volumetric mixing ratio, is related to the mass mixing ratio as follows:

$$r_v = \frac{n_1}{n_2} = \left( \frac{M_2}{M_1} \right) r_m$$

When concentrations are recorded with units of “ppmv”, “ppbv” or “pptv”, these units refer respectively to  $10^6 r_v$ ,  $10^9 r_v$ , or  $10^{12} r_v$  with  $r_v$  given by the above equation.

5. The unit “hertz” (abbreviation Hz) is the proper unit for a periodic sampling frequency and will be used here in place of the more awkward “samples per second.” This usage is favored by the International Bureau of Weights and Measures (cf. [http://www.bipm.org/en/si/si\\_brochure/chapter2/2-2/table3.html#notes](http://www.bipm.org/en/si/si_brochure/chapter2/2-2/table3.html#notes)) when the frequency represented refers to the rate of sampling.
6. In some cases, particularly for older data files, speed has been recorded in units of knots (= 0.514444 m/s) and distance in nautical miles (= 1852 m).

There is a list of symbols used in this report, on page 11.<sup>3</sup> The next table defines some abbreviations and symbols used in this report, in addition to the standard abbreviations for the mks system of units:

abbreviation/symbol	definition <sup>a</sup>
°	degree, angle measurement $\equiv (\pi/180)$ radian
ft	foot $\equiv 0.3048$ m
mb	millibar $\equiv 100$ Pa $\equiv 1$ hPa
ppmv	parts per million by volume (see subsection 2.1 item 4)
ppbv	parts per billion ( $10^9$ ) by volume (see subsection 2.1 item4)
pptv	parts per trillion ( $10^{12}$ ) by volume (see subsection 2.1 item4)
n mi	nautical mile $\equiv 1852$ m
kt	knot (n mi/hour) $\equiv (1852/3600)$ m/s = 0.514444... m/s

<sup>a</sup>where the symbol  $\equiv$  is used, the relationship is exact by definition

## 2.2 Variables Used To Denote Time

Although there are some exceptions in old archived data files, the data in all modern output files are referenced to Coordinated Universal Time (UTC). The time and date of the data acquisition system are synchronized to the Global Positioning System (GPS) at the beginning of each flight, and for data acquired by the present ADS-3 (NIDAS) data acquisition system time is synchronized continuously with the GPS time. Time variables vary for older archived data files; some of the following are obsolete, but are included here for reference because they are important to those wanting to use those archives.

### Time (s): Time

This is the reference-time *counter* for the output data files, used by data system versions beginning with ADS-3. It is an integer output at 1 sample per second *and has an initial value of zero at the start of the flight*. Add this to the “Time:units” attribute found in the NETCDF header section for this variable to obtain the UTC measurement time.

<sup>3</sup> Some symbols used only once and defined where they are used are omitted from this list

Example attribute:

```
Time:units = ‘‘seconds since 2006-04-26 12:55:00 +0000’’ ;
```

For code examples that show how to use “Time” see:

```
http://www.eol.ucar.edu/raf/Software/TimeExamp.html
```

**Reference Start Time (s): base\_time (*Obsolete; versions before ADS-3 only*)**

This is the reference time for the NETCDF output data files for data system versions before ADS-3. It represents the time of the first data record. Its format is Unix time (elapsed seconds after midnight 1 January 1970). Use this measurement and add time\_offset (below) to obtain the time for each data record. (Note: base\_time is a single scalar, not a “record” variable, so it occurs just once in the output file.)

**Time Offset from Reference Start Time (s): time\_offset (*Obsolete*)**

This is the time offset from base\_time of each data record used for the NETCDF output files produced by data system versions before ADS-3. It starts at zero (0) and increments each second, so it can also be thought of as a record counter. Use this measurement and add base\_time to obtain the time for each data record.

**Raw Tape Time (hour, minute, s): HOUR, MINUTE, SECOND (*Obsolete*)**

These three time variables are recorded directly from the aircraft’s data system. Since ADS-3, this information is replaced by the “Time” variable and the “Time:units” attribute of that variable.

**Date (m, d, y): MONTH, DAY, YEAR (*Obsolete*)**

These three variables represent the date when the aircraft’s data system began recording data. They are repeated as 1 Hz variables but are NOT incremented if the time rolls over to the next day. Use base\_time and time\_offset for reference timing. Since ADS-3, this information is replaced by the “Time” variable and the “Time:units” attribute of that variable.

## 2.3 Other Comments On Terminology

### 2.3.1 Variable Names In Equations

This report often uses variable names in equations, and sometimes there is potential for confusion because the variable names consist of multiple characters. In many cases, to denote that the variable name is the variable in the equation (as opposed to each of the letters in the variable name representing quantities to be multiplied together), the variable name has been enclosed in brackets, as in {TASX}. In addition, variable names are displayed with upright Roman character sets, while other nomenclature in equations is represented by slanted (script) character sets as is conventional for mathematical equations. In cases where code segments (usually expressed in C code) are included to document how calculations are performed, typewriter character sets indicate that the segment is a representation of how the processing could be coded. Such a code segment is not always a direct copy of the code in use, but such code is often the most convenient way to express the algorithm in use.



### 2.3.2 Distinction Between Original Measurements and Derived Measurements

Many of the variables in the data files and in this report are derived from combinations of measurements. The terms “raw” or “original” measurement are sometimes used for a minimally processed output received directly from a sensor or instrument. Such measurements may be converted to engineering units via calibration coefficients, but otherwise they are a direct representation of the output from a sensor.<sup>4</sup> In contrast, derived variables (e.g., potential temperature) depend on one or more “raw” measurements and are not direct results of output from an instrument. For most derived measurements, a box that follows an introductory comment is used in this report to document the processing algorithm. The box has a line dividing top from bottom; in the top are definitions used and explanations regarding variables that enter the calculation, while the bottom portion contains the equation, algorithm, or code segment that documents how the variable is calculated.

### 2.3.3 Dimensions in Equations

An effort has been made to avoid dimensions in equations except where it would be awkward otherwise. Some scale factors are introduced for only this purpose (e.g., to avoid dimensions in arguments to logarithmic or exponential functions), and some effort was made to isolate dimensions to defined constants rather than requiring that variables in equations be used with specific units. However, some exceptions remain to be consistent with historical usage.

---

<sup>4</sup>Calibration coefficients, e.g. those used to convert from voltage output from an analog sensor to a measured quantity with physical units like °C), are not included or discussed in this report but are part of project reports and, in recent years, are included in the header of the NETCDF file.

## 3 THE STATE OF THE AIRCRAFT

The primary sources of information on the location and motion of the aircraft are from inertial reference systems and from global positioning systems. Both are described in this section, as well as combined results that merge the best features of each into composite variables for location and motion.

### 3.1 Inertial Reference Systems

An Inertial Reference System (IRS) or Inertial Reference Unit (IRU) provides measurements of aircraft position, velocity relative to the Earth, acceleration and attitude or orientation. For the GV, the system is a Honeywell Laseref III/IV Inertial Reference System. Data from the IRS come via a serial digital bit stream (the ARINC digital bus) to the ADS (Aircraft Data System). Because there is some delay in transmission and recording of these variables, adjustments for this delay are made when the measurements are merged into the processed data files, as documented in the NetCDF header files. Some of the variables are recorded only on the original “raw” data tapes and are not usually included on final archived data files; these are discussed at the end of this section. See also Section XXX for information on results from inertial systems that were used prior to installation of the present Honeywell systems.

An Inertial Reference System “aligns” while the aircraft is stationary by measurement of the variations in its reference frame caused by the rotation of the Earth. Small inaccuracy in that alignment lead to a “Schuler oscillation” that produces oscillatory errors in position and other measurements, with a period  $\tau_{Sch}$  of about 84 minutes ( $\tau_{Sch} = 2\pi\sqrt{R_e/g}$ ). Position errors of less than 1.0 n mi/hr are within normal operating specifications. See Section 3.4 for discussion of additional variables, similar to the following, for which corrections are made for these errors via reference to data from a Global Positioning System.

#### **Latitude (°): LAT**

This is the aircraft latitude, output from the IRS at 10 Hz. Positive values are north of the equator; negative values are south. The resolution is 0.00017° and the accuracy is reported by the manufacturer to be 0.164° after 6 h of flight.

#### **Longitude (°): LON**

This is the aircraft longitude, output from the IRS at 10 Hz. Positive values are east of the prime meridian; negative values are west. The resolution is 0.00017° and the accuracy is reported by the manufacturer to be 0.164° after 6 h of flight.

#### **Aircraft True Heading (°): THDG**

This is the aircraft’s true heading, output from the IRS at 25 Hz. The resolution is 0.00017° and the accuracy is quoted by the manufacturer as 0.2° after 6 h of flight. “True” distinguishes the heading from the magnetic heading, the heading that would be measured by a magnetic-compass needle.

#### **Aircraft Pitch Attitude Angle (°): PITCH**

This is the aircraft’s pitch angle, provided from the IRS at 50 Hz. Positive values correspond to the nose of the aircraft pointing above the horizon. The resolution is 0.00017° and the accuracy is quoted by the manufacturer as 0.05° after 6 h of flight.

**Aircraft Roll Attitude Angle (°): ROLL**

This is the aircraft's roll angle, output from the IRS at 50 Hz. Positive angles occur with the starboard (right) wing down (i.e., a clockwise rotation from level when facing forward in the aircraft). The resolution is  $0.00017^\circ$  and the accuracy is quoted by the manufacturer as  $0.05^\circ$  after 6 h of flight..

**Aircraft Vertical Acceleration ( $\text{m s}^{-2}$ ): ACINS**

This is the output from the IRS vertical accelerometer with its internal drift removed via pressure damping.<sup>5</sup> Positive values are upward. The sample rate is 50 Hz and the resolution is  $0.0024 \text{ m s}^{-2}$ .

**Computed Aircraft Vertical Velocity (m/s): VSPD**

This is the upward velocity of the aircraft provided directly by the IRS. It is determined in the IRS by integration of the vertical acceleration, with damping based on measured pressure to correct for accumulated errors in the integration of acceleration. The sample rate is 50 Hz with a resolution of  $0.00016 \text{ m/s}$ . The Honeywell Laseref IRS employs a baro-inertial loop, similar to that described below for WP3 and the Litton LTN-51, to update the value of the acceleration. It is also filtered within the IRS so that there is little variance with frequency higher than 0.1 Hz.

**Pressure-Damped Aircraft Vertical Velocity (m/s): WP3 (obsolete)**

This was a derived output incorporating a third-order damping feedback loop to remove the drift from the inertial system's vertical accelerometer (ACINS or VZI) using pressure altitude (PALT) as a long-term, stable reference. Positive values are up. The Honeywell IRS now in use provides its own version of this measurement, VSPD, and WP3 is now considered obsolete (and in any case should not be calculated from ACINS as provided by the Honeywell Laseref IRS because that ACINS already incorporates pressure damping). Documentation is included here because many old data files include this variable. Note that "pressure altitude" is not a true altitude but an altitude equivalent to the ambient pressure in a standard atmosphere, so updating a variable integrated from inertial measurements to this value can introduce errors vs. the true altitude.. WP3 was calculated by the data-processing software as follows (with coefficients in historical use and not updated to the recommendations elsewhere in this technical note):<sup>6</sup>

<sup>5</sup>For earlier projects using the Litton LTN-51 INS, this is a direct measurement without adjustment for changes in gravity during flight and without pressure-damping. Previous use employed a baro-inertial loop to compensate for drift in the integrated measurement. See the discussion of WP3 below.

<sup>6</sup>Regarding signs, note that ACINS is a number near zero, not near  $g$ , and so already has the estimated acceleration of gravity removed. The assumption made in the following is that the INS will report values adjusted for the gravitational acceleration *at the point of alignment*, which would be  $G_L$ . If  $g_F$ , the estimate for gravity at the flight altitude (palt) and latitude (lat), is *smaller* than  $G_L$  then the difference ( $G_L - g_f$ ) will be positive; this will correct for the reference value for ACINS being the gravity measured at alignment ( $G_L$ ) when it should actually be the sensed gravity ( $g_f$ ) at the measurement point, so to obtain (sensed acceleration -  $g_f$ ) it is necessary to add ( $G_L - g_f$ ) to ACINS, *increasing* "acz" in this case. However, the situation with "vcorac" is reversed: "vcorac" is a positive term for all eastward flight, for example, but in that case the motion of the aircraft makes objects seem lighter (i.e., they experience less acceleration of gravity) than without such flight. ACINS is positive upward so it represents a net acceleration of the aircraft upward (as imposed by the combination of gravity and the lift force of the aircraft). To accomplish level flight in these circumstances, the aircraft must actually accelerate downward so the accelerometer will experience a negative excursion relative to slower flight. To compensate, "vcorac" must

$$g_1 = 9.780356 \text{ m s}^{-2}$$

$$a_1 = 0.31391116 \times 10^{-6} \text{ s}^{-2}$$

$$a_2 = .0052885 \text{ (dimensionless)}$$

VEW (VNS) = eastward (northward) groundspeed of the aircraft (see below)

LAT = latitude measured by the IRS [°]

$C_{dr} = \pi/180^\circ$  = conversion factor, degrees to radians

PALT = pressure altitude of the aircraft

$\Omega$  = angular rotation of the earth =  $7.292116 \times 10^6$  radians/s

$R_E$  = radius of the Earth =  $6.371229 \times 10^6$  m

$g_f$  = local gravity corrected for latitude and altitude

$V_c$  = correction to gravity for the motion of the aircraft

$G_L$  = local gravity at the location of IRU alignment, corrected to zero altitude

$\{C[0], C[1], C[2]\}$  = feedback coefficients,  $\{0.15, 0.0075, 0.000125\}$  for 125-s response

1. From the pressure altitude PALT (in m) and the latitude LAT (converted to radians), estimate the acceleration of gravity:

$$g_f = g_1 (1 + a_2 \sin^2(C_{dr}\{LAT\}) + a_1 \{PALT\})$$

2. Determine corrections for Coriolis acceleration and centrifugal acceleration:

$$a_c = 2\Omega\{VEW\} \cos(C_r\{LAT\}) + \frac{\{VEW\}^2 + \{VNS\}^2}{R_E}$$

3. Estimate the acceleration experienced by the aircraft as follows:

$$acz = a_z = \{ACINS\} + G_L - g_f + a_c$$

4. Use a feedback loop to update the integrated value of the acceleration. The following code segment uses  $acz=a_z$ ,  $\text{deltaT}[]$  to represent the time between updates, and  $hi3$ ,  $hx$ , and  $hxx$  to store the feedback terms:

```
wp3[FeedBack] += (acz - C[1] * hx[FeedBack]
- C[2] * hxx[FeedBack]) * deltaT[FeedBack];
```

5. Update the feedback terms:

```
hi3[FeedBack] = hi3[FeedBack] + (wp3[FeedBack]
- C[0] * hx[FeedBack]) * deltaT[FeedBack];
hx[FeedBack] = hi3[FeedBack] - palt;
hxx[FeedBack] = hxx[FeedBack]
+ hx[FeedBack] * deltaT[FeedBack];
```

6. Set WP3 to the average of the last wp3 result and the current wp3 result.

make a positive contribution to remove that negative excursion from “acz”. In the conceptual extreme that the aircraft flies fast enough for the interior to appear weightless, ACINS would reduce to  $-1 \cdot G_L$  and vcorac would increase to  $+G_L$ , leaving acz near zero as required if the aircraft were to remain in level flight in the rotating frame

**Inertial Altitude (m): ALT**

This is the altitude of the aircraft as provided by the IRS, with pressure damping applied within the IRU to the integrated aircraft vertical velocity to avoid the accumulation of errors. The value therefore is updated to the pressure altitude, not the geometric altitude, and should be regarded as a measurement of pressure altitude where short-term variations are provided by the IRU in a way that uses the pressure altitude as a baseline for longer-term updating. The sample rate is 25 Hz with a resolution of 0.038 m.

**Aircraft Ground Speed (m/s): GSF**

This is the ground speed of the aircraft as provided by the IRU (at 10 Hz). The resolution is 0.0020 m/s.

**Aircraft Ground Speed East Component (m/s): VEW**

The IRU provides this measurement of the east-directed component of ground speed, at a rate of 10 Hz. The resolution is 0.0020 m/s.

**Aircraft Ground Speed North Component (m/s) VNS**

The IRU provides this measurement of the north-directed component of ground speed, at a rate of 10 Hz. The resolution is 0.0020 m/s.

**Distance East/North of a Reference (km): DEI/DNI**

These are derived outputs obtained by subtracting a fixed reference position from the current position. The values are determined from measurements of latitude and longitude and converted from degrees to distance in a rectilinear coordinate system. The reference position can be either the starting location of the flight or a user-defined reference point (e.g., the location of a project radar). The accuracy of these values is dependent on the accuracy of the source of latitude and longitude measurements (see LAT and LON), and the calculations are only appropriate for short distances because they do not take into account the spherical geometry of the Earth..

$LON_{ref}$  = reference longitude (°)

$LAT_{ref}$  = reference latitude (°)

$SF_{ref}$  = reference scale factor = 111.12 km /°

$$DEI = (\{LON\} - \{LON_{ref}\})SF_{ref} \cos(\{LAT\})$$

$$DNI = (\{LAT\} - \{LAT_{ref}\})SF_{ref}$$

**Radial Azimuth/Distance from Fixed Reference: FXAZIM, FXDIST**

Derived calculations of the radial azimuth (°) and distance (km) from a fixed reference position (a user-specified reference latitude and longitude) to the aircraft's location, as discussed in the preceding paragraph. These are calculated by rectangular-to-polar conversion of DEI/DNI.

**–RAW IRS VARIABLES NOT INCLUDED IN NORMAL DATA FILES:–**

The following IRS variables are not normally included in archived data files, but their values are recorded by the ADS and can be obtained from the original “raw” data files:

**Raw Lateral Body Acceleration (m/s<sup>2</sup>): BLATA**

The raw output from the IRU lateral accelerometer. Positive values are toward the starboard, normal to the aircraft center line. The sample rate is 50 Hz with a resolution of 0.0024 m s<sup>-2</sup>.

**Raw Longitudinal Body Acceleration (m/s<sup>2</sup>): BLONA**

The raw output from the IRU longitudinal accelerometer. Positive values are in the direction of the nose of the aircraft and parallel to the aircraft center line. The sample rate is 50 Hz with a resolution of 0.0024 m s<sup>-2</sup>.

**Raw Normal Body Acceleration (m/s<sup>2</sup>): BNORMA**

The raw output from the IRU vertical accelerometer. Positive values are upward in the reference frame of the aircraft, normal to the aircraft center line and lateral axis. The sample rate is 50 Hz with a resolution of 0.0024 m s<sup>-2</sup>.

**Raw Body Pitch Rate (°/s): BPITCHR**

The raw output of the IRU pitch rate gyro. Positive values indicate the nose moving upward and refer to rotation about the aircraft’s lateral axis. The sample rate is 50 Hz with a resolution of 0.0039°/s.

**Raw Body Roll Rate (°/s): BROLLR**

The raw output of the IRU roll rate gyro. Positive values indicate starboard wing moving down and refer to rotation about the aircraft center line. The sample rate is 50 Hz with a resolution of 0.0039°/s.

**Raw Body Yaw Rate (°/s): BYAWR**

The raw output of the IRU yaw rate. Positive values represent the nose turning to the starboard and refer to rotation about the aircraft’s vertical axis. The sample rate is 50 Hz with a resolution of 0.0039°/s.

## 3.2 Global Positioning Systems

GPS variables aboard RAF aircraft are provided by a Trimble TANS-III GPS receiver. It has the ability to track up to 6 satellites at a time but needs only 4 to provide 3-dimensional position and velocity data (3 satellites for 2-dimensions). The accuracy of the position measurements is stated to be 25 meters (horizontal) and 35 meters (vertical) under “steady-state conditions.”<sup>7</sup> Likewise, velocity measurements are within 0.2 m/s for all axes. Measurement resolution is that

---

<sup>7</sup>Note: The GPS signals at one time suffered from “selective availability,” a US DOD term for a dithered signal that degrades GPS absolute accuracy to 100 meters. This was especially noticeable in the altitude measurement, so GALT normally was not useful. As of 1 May 2000, selective availability was deactivated to allow everyone to obtain better position measurements. (See the Interagency GPS Executive Board web site for more information.)

of 4-byte IEEE format (about 6 significant digits). All variables are output at a sample rate of 1 Hz.

Some of the following variables are also available from a second unit and are qualified by the name of that unit; e.g., GGLAT\_GMN for GGLAT as measured by a Garmin GPS unit. In addition, some of the measurements from the GPS units that are part of the aircraft avionics systems are recorded; these are denoted by a suffix “\_G” or “\_A”.

**GPS Latitude (°): GGLAT, LAT\_G; also formerly GLAT**

The aircraft latitude output from the GPS. Positive values are north of the equator; negative values are south. GGLAT is provided by the data-system GPS; LAT\_G and LATF\_G are from the avionics system GPS. LATF\_G is a fine-resolution measurement that requires special processing.

**GPS Longitude (°): GGLON, LON\_G; also formerly GLON**

The aircraft longitude output from the GPS. Positive values are east of the prime meridian; negative are west. GGLON is provided by the (or a) data-system GPS; LON\_G and LONF\_G are from the avionics system GPS. LONF\_G is a fine-resolution measurement that requires special processing.

**GPS Ground Speed (m/s): GSF\_G, GGSPD**

The aircraft ground speed output from the GPS. GSF\_G originates from an avionics-system GPS; GGSPD originates from a data-system GPS.

**GPS Ground Speed Vector East Component (m/s): GGVEW, VEW\_G**

The east component of ground speed as measured by the GPS. VEW\_G originates from an avionics-system GPS; GGVEW originates from a data-system GPS.

**GPS Ground Speed Vector North Component (m/s): GGVNS, VNS\_G**

The northward component of ground speed as measured by a GPS unit. VNS\_G originates from an avionics-system GPS; GGVNS originates from a data-system GPS.

**GPS-Computed Aircraft Vertical Velocity (m/s): VSPD\_G, (obsolete) GVZI**

The aircraft vertical velocity provided by a GPS unit. Positive values are upward.

**GPS Altitude (m): GGALT, ALT\_G**

The aircraft altitude output from the GPS. The measurement is with respect to a geopotential surface (MSL) defined by the GPS’s built-in earth model. Positive values are above the reference surface. GGALT originates from a data-system GPS; ALT\_G originates from an avionics-system GPS.

**GPS Aircraft Track Angle (°): GGTRK, TKAT\_G**

The direction of the aircraft track (degrees clockwise from true north) as measured by a data-system GPS (GGTRK) or an avionics-system GPS (TKAT\_G).

**GPS Height of the Geoid (m): GGEIDHT**

Height of geoid (MSL) above the WGS84 ellipsoid.

**GPS Satellites Tracked: GGNSAT**

The number of satellites tracked by the GPS unit.

**GPS Mode: GGQUAL**

Quality flag: 0, 1, 2 for invalid, normal GPS, and differential GPS, respectively.

**GPS Mode: GMODE (obsolete)**

This is the former output from the GPS indicating the mode of operation. The normal value is 4, indicating automatic (not manual) mode and that the receiver is operating in 4-satellite (as opposed to fewer) mode.

**GPS Status: GGSTATUS, GSTAT\_G, (obsolete) GSTAT**

The status of the GPS receiver. A value of 1 indicates that the receiver is operating normally; a value of 0 indicates a warning regarding data quality. GGSTATUS indicates the status of the data-system GPS; GSTAT\_G indicates the status of the avionics-system GPS. The obsolete variable GSTAT, formerly used for the same purpose, has the reverse meaning: A value of 0 indicates normal operation and any other code indicates a malfunction or warning regarding poor data accuracy.

### 3.3 Other Measurements of Aircraft Altitude

**Altitude, Reference (MSL): ALT\_X, GALT\_C**

This is the derived altitude above the geopotential surface obtained primarily from GALT, the GPS altitude, with help from another reference altitude, typically ALT, the inertial altitude. The GPS signals at times are degraded, most often during aircraft turns. Two GPS status measurements are used to detect this, but sometimes the information comes too late. A 10-second running average is calculated of the difference between the GPS altitude and the reference altitude. When the sample-to-sample altitude difference changes more than 50 meters or when the GPS status detects a degraded signal, the altitude from this measurement changes from GPS altitude to an adjusted reference altitude (defined as reference altitude plus the running difference average). When the GPS altitude is again “good” and to avoid a sudden altitude transition, the output linearly steps back to the GPS altitude over the next 10 seconds. \*\*\* *REVISE THIS, NEW ALGORITHM*

**ISA Pressure Altitude (m): PALT**

This derived altitude is obtained from the reference barometric (static or ambient) pressure measurement using the International Standard Atmosphere (ISA), equivalent to the reference atmosphere for aviation operations worldwide.<sup>8</sup> The pressure altitude is best interpreted as a variable equivalent to the measured pressure, not as a geometric altitude. In the following description of the algorithm, some constants (identified by the symbol †) are specified as part of the ISA and so should not be “improved” to more modern values such as those given in the table in section 1.3 (e.g.,  $R'_0$ ).<sup>9</sup> A note at this URL describes the pressure

<sup>8</sup>See “U.S. Standard Atmosphere, 1976”, NASA-TM-A-74335, available for download at this URL.

<sup>9</sup>Prior to and including some projects in 2010, processing used slightly different coefficients: for aircraft other than the GV,  $T_0/\lambda$  was represented by -43308.83, the reference pressure  $p_0$  was taken to be 1013.246, and the exponent  $x$  was represented numerically by 0.190284. For the GV, the value of  $T_0/\lambda$  was taken to be 44308.0, the transition pressure  $p_T$  was 226.1551 hPa,  $x = 0.190284$ , and coefficient  $\frac{R'_0 T_T}{g M_d}$  was taken to be 6340.70 m instead of 6341.620 m as obtained below. The difference between these older values and the ones recommended below is everywhere less than 10 m and so is small compared to the expected uncertainty in pressure measurements,



altitude in more detail and documents the change that was implemented in November 2010.

---

because 1 hPa change in pressure leads to a change in pressure altitude that varies from about 8–40 m over the altitude range of the GV .)

$T_0 = 288.15$  K, reference temperature†  
 $\lambda = -0.0065$  K/m = the lapse rate for the troposphere†  
 $p$  = measured static (ambient) pressure, hPa, usually from PSXC  
 $p_a = 1013.25$  hPa, reference pressure for PALT=0†  
 $M'_d = 28.9644$  kg/kmol = molecular weight of dry air, ISA definition†  
 $g' = 9.80665$  m s<sup>-2</sup>, acceleration of gravity†  
 $R'_0$  = universal gas constant, defined† as  $8.31432 \times 10^3$  J kmol<sup>-1</sup> K<sup>-1</sup>  
 $z_T$  = altitude of the ISA tropopause = 11,000 m†  
 $x = R'_0 \lambda / (M'_d g') \approx 0.1902632$  (dimensionless)<sup>a</sup>

For pressure > 226.3206 hPa (equivalent to a pressure altitude <  $z_T$ ):

$$\text{PALT} = - \left( \frac{T_0}{\lambda} \right) \left( 1 - \left( \frac{p}{p_a} \right)^x \right)$$

otherwise, if  $T_T$  and  $p_T$  are respectively the temperature and pressure at the altitude  $z_T$ :

$$T_T = T_0 + \lambda z_T = 216.65 \text{ K}$$

$$p_T = p_a \left( \frac{T_0}{T_T} \right)^{\frac{g' M'_d}{\lambda R'_0}} = 226.3206 \text{ hPa}$$

$$\text{PALT} = z_T + \frac{R'_0 T_T}{g' M'_d} \ln \left( \frac{p_T}{p} \right)$$

which, after conversion from natural to base-10 logarithm, is coded to be equivalent to the following:

```

// transition pressure at the assumed ISA tropopause:
#define ISAP1 226.3206
    // reference pressure for standard atmosphere:
#define ISAP0 1013.25
if (psxc > ISAP1)

    palt = 44330.77 * (1.0 - pow(psxc/ISAP0, 0.1902632));
else

    palt = 11000.0 + 14602.12 * log10(ISAP1/psxc);

```

<sup>a</sup>This is the value, rounded to seven significant figures, that is used for data processing.

### Geometric Radio Altitude (m): HGM

This is the distance to the surface below the aircraft, measured by a radio altimeter. The maximum range is 762m (2,500 ft). The instrument changes in accuracy at an altitude of

152 m: The estimated error from 152 m to 762 m is 7%, while the estimated error for altitudes below 152 m is 1.5 m or 5%, whichever is greater.

**Geometric Radar Altitude (Extended Range) (APN-159) (m): HGME**

There are two outputs from an APN-159 radar altimeter, one with coarse resolution (CHGME) and one with fine resolution (HGME). Both raw outputs cycle through the range 0-360 degrees, where one cycle corresponds to 4,000 feet for HGME and to 100,000 feet for CHGME. To resolve the ambiguity arising from these cycles, 4,000-foot increments are added to HGME to maintain agreement with CHGME. This preserves the fine resolution of HGME (1.86 m) throughout the altitude range of the APN-159.

**Geometric Radar Altitude (Extended Range) (APN-232) (m): HGM232**

Altitude above ground as measured by an APN-232 radar altimeter.

**Pressure-Damped Inertial Altitude (m): HI3 (obsolete)**

The aircraft altitude obtained from the twice-integrated IRU acceleration (ACINS), pressure-adjusted to obtain long-term agreement with PALT. Note that this variable has mixed character, producing short-term variations that accurately track the inertial system changes but with adjustment to the pressure altitude, which is not a true altitude. The variable is not appropriate for estimates of true altitude, but proves useful in the updating algorithm used with the LTN-51 IRU for vertical wind. See the discussion of WP3 on page 19. This variable is now obsolete.

### 3.4 Combining IRS and GPS Measurements

Measurements from the global positioning and inertial reference systems are combined to produce new variables that take advantage of the strengths of each, so that the resulting variables have the long-term stability of the GPS and the short-term resolution of the IRU. This section describes some variables that result from this blending of variables. These corrected variables are usually the best available when the GPS and IRS are both functioning.

One can determine if the GPS is functioning by examining the GPS status variables described in the previous section or by looking for spikes or “flat-lines” in the data. If the GPS data are missing for a short time (a few seconds to a minute), accuracy is not affected. However, longer dropouts will result in accuracies degrading toward those of the IRU. Without the GPS or another ground reference, the IRS error cannot be determined empirically, and one should assume that it is within the manufacturer’s specification (1 nautical mile of error per hour of flight, 90% CEP). When the GPS is active, RAF estimates that the correction algorithm produces a position with an error less than 100 meters. Due to the nature of the algorithm, the error will increase from about 100 meters to the IRU specification in about one-half hour after GPS information is lost.

**GPS-Corrected Inertial Ground Speed Vector, (m/s): VEWC, VNSC**

These variables result from combining GPS and IRU output of the east and north components of ground speed from a complementary-filter algorithm. Positive values are toward the east and north, respectively. The smooth, high-resolution, continuous measurements from the inertial navigation system, {VNS, VEW}, which can slowly accumulate errors over time, are combined with the measurements from the GPS, {GVNS, GVEW}, which

have good long-term stability, via an approach based on a complementary filter. A low-pass filter,  $F_L(\{GVNS, GVEW\})$ , is applied to the GPS measurements of groundspeed, which are assumed to be valid for frequencies at or lower than the cutoff frequency  $f_c$  of the filter. Then the complementary high-pass filter, denoted  $(1 - F_L)(\{VNS, VEW\})$ , is applied to the IRS measurements of groundspeed, which are assumed valid for frequencies at or higher than  $f_c$ . Ideally, the transition frequency would be selected where the GPS errors (increasing with frequency) are equal to the IRS errors (decreasing with frequency). The filter used is a three-pole Butterworth lowpass filter, coded following the algorithm described in Bosic, S. M., 1980: *Digital and Kalman filtering : An Introduction to Discrete-Time Filtering and Optimum Linear Estimation*, p. 49. The digital filter used is recursive, not centered, to permit calculation during a single pass through the data. If the cutoff frequency lies where both the GPS and IRU measurements are almost the same, then the detailed characteristics of the filter (e.g., phase shift) in the transition region do not matter because the complementary filters have cancelling effects when applied to the same signal. The transition frequency  $f_c$  was chosen to be (1/600) Hz. The Butterworth filter was chosen because it provides flat response away from the transition. The net result then is the sum of these two filtered signals, calculated as described in the following box:

VEW = IRS-measured east component of the aircraft ground speed  
VNS = IRS-measured north component of the aircraft ground speed  
GGVEW = GPS-measured east component of the aircraft ground speed  
GGVNS = GPS-measured north component of the aircraft ground speed  
 $F_L()$  = three-pole Butterworth lowpass recursive digital filter

$$\{VNSC\} = F_L(\{GGVNS\}) + (1 - F_L)(\{VNS\})$$

$$\{VEWC\} = F_L(\{GGVEW\}) + (1 - F_L)(\{VEW\})$$

This result is used as long as the GPS signals are continuous and flagged as being valid. When that is not the case, some means is needed to avoid sudden discontinuities in velocity (and hence windspeed), which would introduce spurious effects into variance spectra and other properties dependent on a continuously valid measurement of wind. To extrapolate measurements through periods when the GPS signals are lost (as sometimes occurs, for example, in turns) a fit is determined to the difference between the best-estimate variables  $\{VNSC, VEWC\}$  and the IRS variables  $\{VNS, VEW\}$  for the period before GPS reception was lost, and that fit is used to extrapolate through periods when GPS reception is not available. The procedure is as follows:

1. If GPS reception has never been valid earlier in the flight, use the IRU values without correction.
2. If GPS reception is lost after a valid complementary-filter correction has been obtained earlier using the procedure described above, but no valid Schuler-oscillation fit has been accumulated as described in [3.] below, use the correction factors from the complementary filter reduced by a factor of 0.997 each second, producing an exponential decay back toward the IRS values with decay time constant of about 5.6 min.
3. When GPS reception is good, update a least-squares fit to the difference between the GPS and IRU groundspeeds, for each component. The errors are assumed to result primarily from a Schuler oscillation, so the three-term fit is of the form  $\Delta = a_1 + a_2 \sin(\Omega_{Sch}t) + a_3 \cos(\Omega_{Sch}t)$ , where  $\Omega_{Sch}$  is the angular frequency of the Schuler oscillation (taken to be  $2\pi/(5067s)$ ) and  $t$  is the time since the start of the flight. A separate fit is used for each component of the velocity and each component of the position (discussed below under LATC and LONC). The fit matrix used to determine these coefficients is updated each time step but the accumulated fit factors decay exponentially with a 30-min decay constant, so the terms used to determine the fit are exponentially weighted over the period of valid data with a time constant that decays exponentially into the past with a characteristic time of 30 min. This is long enough to determine a significant portion of the Schuler oscillation but short enough to emphasize recent measurements of the correction.
4. When GPS data become invalid, if sufficient data (spanning 30 min) have been accumulated, invert the accumulated fit matrices to determine the coefficients  $\{a_1, a_2, a_3\}$  and then use the formula for  $\Delta$  in the preceding step to extrapolate the correction to the IRS measurements while the GPS measurements remain invalid. Doing so immediately would introduce a discontinuity in  $\{VNSC, VEWC\}$ , however, so the correction  $\Delta$  is introduced smoothly by adjusting  $\{VNSC, VEWC\}$  smoothly as follows:  $\Delta' = (1 - \eta)(VNSC_0 - GVNS_0) + \eta\Delta$  where  $\Delta'$  is the sequentially adjusted correction,  $(VNSC_0 - GVNS_0)$  is the difference preserved from the last time the GPS groundspeed was valid, and  $\eta = 0.997s^{-1}$  is chosen to give a decaying transition with a time constant of about 5.5 min. This has the potential to introduce some artificial variance at this scale and so should be considered in cases where variance spectra are analyzed in detail, but it has much less influence on such spectra than would introducing a discontinuous transition. Ideally, the current fit and the last filtered discrepancy  $(VNSC_0 - GVNS_0)$  should be about equal, so this should not introduce a significant change.

#### **GPS-Corrected Inertial Latitude and Longitude (°): LATC, LONC**

Combined GPS and IRS output of latitude and longitude. Positive values are north and east, respectively. These variables are the best estimate of position, obtained by the following approach:

LAT = latitude measured by the IRS

LON = longitude measured by the IRS

GGLAT = latitude measured by the GPS

GGLON = longitude measured by the GPS

VNSC = aircraft ground speed, north component, corrected

VEWC = aircraft ground speed, east component, corrected

1. Initialize the corrected position at the IRS position at the start of the flight or after any large change ( $>5^\circ$ ) in the IRS position.
2. Integrate forward from that position using the aircraft groundspeed with components {VNSC,VEWC}. Note that in the absence of GPS information this will introduce long-term errors because it does not account for the Earth's spherical geometry. It provides good short-term accuracy, but the GPS updating in the next step is needed to compensate for the difference between a rectilinear frame and the Earth's spherical coordinate frame and provides a smooth yet accurate track.
3. Use an exponential adjustment to the GPS position, with time constant that is typically about 100 s.<sup>a</sup>
4. To handle periods when the GPS becomes invalid, use an approach analogous to that for groundspeed, whereby a Schuler-oscillation fit to the difference between the GPS and IRS measurements is developed and used to extrapolate through periods when the GPS is invalid.

<sup>a</sup>specifically,  $LATC \pm \eta(GLAT-LATC)$  with  $\eta = 2\pi/(600\text{ s})$

## 4 THE STATE OF THE ATMOSPHERE

### 4.1 General Information On Variable Names

Measurements of meteorological state variables like pressure, temperature, water vapor pressure often are made at various locations on an aircraft. To distinguish among similar measurements, many variable names incorporate an indication of where the measurement was made. In this document, locations in variable names are represented by “x”, where “x” may represent the following:

Character	Location
B	bottom (or bottom-most)
B	(obsolete) boom
F	fuselage
G	(obsolete) gust probe
R	radome
T	top (or top-most)
W	wing

In addition, a true letter ‘X’ (not replaced by the above letters) may be appended to a measurement to indicate that it is the preferred choice used for derived calculations. Other suffixes sometimes used to distinguish among measurements are these: ‘D’ for a digital sensor; ‘H’ for a heated (usually, deiced) sensor, ‘L’ for port side, and ‘R’ for starboard side.

RAF uses the radome gust-sensing technique (Brown, E. N, C. A. Friehe, and D. H. Lenschow, 1983: *Journal of Climate and Applied Meteorology*, **22**, 171–180) as the reference system to measure incidence angles (angles of attack and sideslip). The pressure difference between sensing ports above and below the center line of the radome is used, along with the dynamic pressure measured at a port on the centerline and referenced to the static pressure, to determine the angle of attack, and similarly for the sideslip angle. A Rosemount Model 858AJ gust probe is occasionally used for specialized measurements. The radome measurements are made by differential pressure sensors located in the nose area of the aircraft and connected to the radome by semi-rigid tubing.

### 4.2 Pressure, Temperature, and Humidity

#### **Static Pressure (mb): PSx, PSxC**

The atmospheric pressure at the flight level of the aircraft, measured by a calibrated absolute (barometric) transducer at location x. PSx is the measured static or ambient pressure, and may be affected by local flow-field distortion. PSxC is corrected for local flow-field distortion. (See RAF Bulletin #21.) For output variables PSFD and PSFDC, the letter “D” indicates that the transducer used was a Rosemount Model 1501 digital absolute pressure transducer. For output variable PSFRD, the letters “RD” indicate that the pressure

transducer used was a Ruska Model 7885-1B digital absolute pressure transducer. Other static pressure measurements are made by a Rosemount Model 1201 absolute pressure transducer, an analog transducer used with appropriate calibration coefficients.

#### **Total Temperature (°C): TTx, TTxH**

The recovery temperature is the temperature sensed by a temperature probe that is exposed to the atmosphere. In flight, the temperature is heated above the ambient temperature because it senses the temperature of air near the sensor that has been heated adiabatically during compression as it is brought near the airspeed of the aircraft. These variables are the measurements of that recovery temperature from calibrated temperature sensors at location x. (The name is misleading, but is kept to comply with long-standing practice. These are not true total temperature measurements, for which the air would be at the same speed as the aircraft.) For Rosemount temperature probes, the recovery temperature is near the total temperature, but all probes must be corrected to obtain either true total temperature or true ambient temperature. In the standard output, the variable name also conveys the sensor type: TTx is a measurement from a Rosemount Model 102 non-deiced temperature sensor, while TTxH is the measurement from a Rosemount Model 102 deiced (heated) temperature sensor. Some past experiments also used a reverse-flow temperature housing; the associated variable name for this probe was TTRF.

#### **Ambient Temperature (°C): ATx, ATxH**

The 'x' in the name of the variable used for ambient temperature, ATx, conveys the same information regarding sensor type and location as the variable name used with total (recovery) temperature. See the discussion above regarding TTx. The ambient temperature (also known as the static air temperature) is calculated from the measured recovery temperature, which includes dynamic heating effects caused by the airspeed of the aircraft. The calculated temperature therefore depends on the recovery temperature TTx as well as the dynamic and static pressure, usually respectively QCXC and PSXC. The pressures are first corrected from the raw measurements QCX and PSX to obtain variables that account for deviations caused by airflow around the aircraft and/or position-dependent systematic errors. The basic equations use conservation of energy for a perfect gas undergoing an adiabatic compression.

The following section combines discussion of the calculations of temperature and airspeed, to reflect the linkage between these derived measurements.

Aircraft temperature sensors do not measure the total temperature, but measure the temperature of the air immediately in contact with the sensing element. This air will not have undergone an adiabatic deceleration to zero velocity and hence will have a temperature  $T_r$  somewhat less than  $T_t$ . This temperature is the measured or "recovery" temperature. The ratio of the actual temperature difference attained to the temperature difference relative to the total temperature is defined to be the recovery factor  $\alpha$  :

$$\alpha = \frac{T_r - T_a}{T_t - T_a} \quad (2)$$



From conservation of energy:

$$\frac{U_a^2}{2} + c_p T_a = \frac{U_r^2}{2} + c_p T_r = \frac{U_t^2}{2} + c_p T_t \quad (3)$$

where  $\{U_a, U_r, U_t\}$  are respectively the aircraft true airspeed, the airspeed relative to the aircraft of the air in thermal contact with the sensor, and the airspeed of air relative to the aircraft when fully brought to the motion of the sensor (i.e., zero). The corresponding absolute temperatures (expressed in kelvin) for the same conditions are  $\{T_a, T_r, T_t\}$ , the ambient, recovery, and total temperatures.

Then, from (3),

$$T_a = T_r - \alpha \frac{U_a^2}{2c_p} \quad (4)$$

The temperature sensors used on RAF aircraft are designed to decelerate the air adiabatically to near zero velocity. Recovery factors determined from wind tunnel testing for the Rosemount sensors are 0.95 (non-deiced model) and 0.98 (deiced model).<sup>10</sup> Recovery factors have also been determined from flight maneuvers, often from “speed runs” where the aircraft is flown level through its speed range and the variation of recovery temperature with airspeed is used with (4), with the assumption that  $T_a$  remains constant, to determine the recovery factor. Data files and project summaries normally document what recovery factor was used for processing a particular project.

As can be seen in the above equation, the true airspeed  $U_a$  is used to calculate the ambient temperature  $T_a$ . However, the ambient temperature is also needed to calculate the true airspeed. Therefore the constraints imposed on ambient temperature and true airspeed by the measurements of recovery temperature, dynamic pressure (the pressure measured by a pitot tube pointed into the airstream and assumed to be that obtained when the incoming air is brought to rest relative to the aircraft), and ambient (or “static”) pressure must be used to solve simultaneously for the two unknowns, temperature and airspeed.

The relationship is conveniently derived by first calculating the dimensionless Mach number ( $M$ ), which is the ratio of the airspeed to the speed of sound ( $U_s = \sqrt{\gamma R_d T_a}$  where  $\gamma$  is the ratio of specific heats of air,  $c_p/c_v$ ). The Mach number is a function of air temperature only and can be determined as follows:

a). Express energy conservation, as in (3), in the form

$$d\left(\frac{U_a^2}{2}\right) + c_p dT = 0 \quad (5)$$

b). Use the perfect gas law to replace  $dT$  with  $\frac{pV}{nR}(\frac{dV}{V} + \frac{dp}{p})$  where  $V$  and  $p$  are the volume and pressure of a parcel of air. Then use the expression for adiabatic compression in

<sup>10</sup> The recovery factor determined for the now-obsolete NCAR reverse-flow sensor was 0.6. The recovery factor for the now retired NCAR fast-response (K-probe) temperature sensor was 0.8.

the form  $pV^\gamma = \text{constant}$  to replace the derivative  $dV$  with  $-\frac{1}{\gamma} \frac{dp}{p}$ , leading to the equation:

$$\frac{U_a^2}{2} + c_p T_a = c_p T_a \left( \frac{p_t}{p_a} \right)^{\frac{R}{c_p}} \quad (6)$$

where  $p_t$  is the total pressure (i.e., PSXC+QCXC) and  $p_a$  is the ambient pressure (PSXC).

c). Use the above definition of the Mach number  $M$  ( $M = U_a/U_s$ ) in the form  $U_a^2 = \gamma M^2 R_d T_a$  to obtain:

$$M^2 = \left( \frac{2c_v}{R_d} \right) \left[ \left( \frac{p_t}{p_a} \right)^{\frac{R}{c_p}} - 1 \right] \quad (7)$$

which can be found from  $p_t$  and  $p_a$  alone.

d). Use the expression for ambient temperature in terms of recovery temperature and airspeed, (4), to obtain the temperature in terms of the Mach number and the recovery temperature:

$$\begin{aligned} T_a &= T_r - \alpha \frac{U_a^2}{2c_p} = T_r - \alpha \frac{M^2 \gamma R_d T_a}{2c_p} \\ &= \frac{T_r}{1 + \frac{\alpha M^2 R_d}{2c_v}} \end{aligned} \quad (8)$$

e). Express the true airspeed ( $U_a$ ) as

$$U_a = M \sqrt{\gamma R_d T_a} \quad (9)$$

Then the temperature is found as described in the following box:

TTX = measured recovery temperature ( $T_r$ )  
 QCxC = measured difference between the dynamic and static pressures  
 PSXC = measured ambient pressure, after airflow/location correction ( $p_a$ )  
 MACHx = Mach number based on QCxC and PSXC (there may be several of these)  
 MACHX = Mach number based on QCXC and PSXC (this is the selected best of the MACHx options)  
 $\alpha$  = recovery factor for the particular temperature sensor

From (7),

$$\text{MACH}_x = \left\{ \left( \frac{2c_v}{R_d} \right) \left[ \left( \frac{\{\text{PSXC}\} + \{\text{QCxC}\}}{\{\text{PSXC}\}} \right)^{\frac{R}{c_p}} - 1 \right] \right\}^{1/2} \quad (10)$$

From (8)

$$\text{AT}_x = \frac{(\{\text{TT}_x\} + T_0)}{\left( 1 + \frac{\alpha(\{\text{MACH}_x\})^2 R_d}{2c_v} \right)} - T_0 \quad (11)$$

#### **Dew/Frost Point (°C): DPx**

The dew point or frost point is measured by either an EG&G Model 137, a General Eastern Model 1011B or a Buck Model 1011C dew-point hygrometer. Below 0°C the instrument is assumed to be measuring the frost point, although occasionally in climbs there is a short transition near the freezing level before the condensate on the mirror of the instrument freezes. These are the uncorrected values, so they represent directly what the instrument senses. The dew point is a measure of water vapor pressure and so is dependent on the vapor pressure in the housing being equal to that in the ambient air. This is achieved by appropriate orientation of the sensor housing and, recently, by measurement of the pressure and correction of the measurements, as discussed in regard to DPxC.

#### **Corrected Dew Point (C): DPxC, PSDPx**

The corrected dew point is the dew point estimated from the original measurement, referenced to the equilibrium vapor pressure over a plane water surface in the absence of other gases. Dew/frost point hygrometers measure the equilibrium point in the presence of air, and this affects the measurement in a minor way. Calculation of this variable removes this dependence, so the vapor pressure obtained from the corrected dew or frost point is that vapor pressure corresponding to equilibrium in the absence of air. In addition, if the measurement is below 0°C, it is assumed to be a measurement of frost point and a corresponding dew point is calculated from the measurement (with correction for the influence of the total pressure on the measurement).

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An additional correction is needed in those cases where the pressure in the housing of the instrument (measured as PSDPx) differs from the ambient pressure, because the changed pressure affects the partial pressure of water vapor in proportion to the change in total

pressure and so changes the measured dew point from the desired quantity (that in the ambient air) to that in the housing. This is especially important in the case of the GV because the potential effect increases with airspeed. If the pressure in the housing is measured or otherwise known (e.g., from correlations with other measurements), then this correction can be introduced into the processing algorithm at the same time that the correction for the presence of dry air is introduced. This correction, based on the pressure PSDPx, is included in the following discussion.

The relationship between water vapor pressure and dew or frost point is based on the Murphy and Koop<sup>11</sup> (2005) equations.<sup>12</sup> They express the equilibrium vapor pressure as a function of frost point or dew point *and at a total air pressure  $p$*  in relationships that are equivalent to the following equations:

$$e = e_{s,i}(T_{FP}) = b'_0 \exp(b_1 \frac{(T_0 - T_{FP})}{T_0 T_{FP}} + b_2 \ln(\frac{T_{FP}}{T_0}) + b_3(T_{FP} - T_0)) \quad (12)$$

$$e = e_{s,w}(T_{DP}) = e_0 \exp\left((\alpha - 1)e_6 + d_2\left(\frac{T_0 - T_{DP}}{T_{DP}T_0}\right) + d_3 \ln\left(\frac{T_{DP}}{T_0}\right) + d_4(T_{DP} - T_0)\right) \quad (13)$$

$$f(p, T_P) = 1 + p(f_1 + f_2 T_P + f_3 T_P^2) \quad (14)$$

where  $e$  is the water vapor pressure,  $T_{FP}$  or  $T_{DP}$  is the frost or dew point, respectively, expressed in kelvin,  $T_0=273.15$  K,  $e_{s,i}(T_{FP})$  is the equilibrium vapor pressure over a plane ice surface at the temperature  $T_{FP}$ ,  $e_{s,w}(T_{DP})$  is the equilibrium vapor pressure over a plane water surface at the temperature  $T_{DP}$  (above or below 0°C), and  $f(p, T_P)$  is the enhancement factor at total air pressure  $p$  and temperature  $T_P$ , with  $T_P$  equal to  $T_{DP}$  when above 0°C and  $T_{FP}$  when below 0°C. The enhancement factor is defined so that the ambient vapor pressure  $e_a$  is related to the *measured* dew or frost point (not the dew or frost point equivalent to the saturation vapor pressure at the dew or frost point) by  $e_a = f(p, T_P)e$ . If the effect of the enhancement factor is to be removed in order to report a dew point in correspondence with the saturation vapor pressure, then the effect of the enhancement factor as represented by  $f(p, T_P)$  must be removed from the measurement. The coefficients used in the above formulas are given in the following tables, with the additional definitions that  $\alpha = \tanh(e_5(T - T_x))$ ,  $T_x = 218.8$  K, and  $d_i = e_i + \alpha e_{i+5}$  for  $i = \{2, 3, 4\}$ :

<sup>11</sup>Q. J. R. Meteorol. Soc. (2005), 131, pp. 1539–1565

<sup>12</sup>Prior to 2010, the vapor pressure relationship used was the Goff-Gratch formula as given in the Smithsonian Tables (List, 1980).

Coefficient	Value
$b'_0$	6.11536 hPa
$b_1$	$-5723.265\text{ K}$ ,
$b_2$	3.53068
$b_3$	$-0.00728332\text{ K}^{-1}$
$f_1$	$4.923 \times 10^{-5}\text{ hPa}^{-1}$
$f_2$	$-3.25 \times 10^{-7}\text{ hPa}^{-1}\text{ K}^{-1}$
$f_3$	$5.84 \times 10^{-10}\text{ hPa}^{-1}\text{ K}^{-2}$

coefficient	value
$e_0$	6.091886 hPa
$e_1$	6.564725
$e_2$	-6763.22 K
$e_3$	-4.210
$e_4$	$0.000367\text{ K}^{-1}$
$e_5$	$0.0415\text{ K}^{-1}$
$e_6$	-0.1525967
$e_7$	-1331.22 K
$e_8$	-9.44523
$e_9$	$0.014025\text{ K}^{-1}$

The vapor pressure in the instrument housing,  $e_h$ , is related to the sensed dew or frost point according to equation (12) or (13), but further corrections must also be made for the enhancement factor and to account for possible difference between the pressure in the sensor housing  $p_h$  and the ambient pressure  $p$ :

$$e_a = f(p, T_p) e_h \frac{p}{p_h} \quad (15)$$

Because processing to obtain the corrected dew point DPxC from the ambient vapor pressure  $e_a$  would require difficult inversion of the above formulas, interpolation is used instead. A table constructed from (12) and another constructed from (13), giving vapor pressure as a function of frost point or dew point temperature in 1°C increments from -100 to +50°C, is then used for three-point Lagrange interpolation (via a function described below as  $T_{DP} = F_D(e)$ ) to find dew point temperature from vapor pressure.<sup>13</sup> Tests of these interpolation formulas against high-accuracy numerical inversion of formulas (12) and (13) showed that the maximum error introduced by the interpolation formula was about 0.004°C and the standard error about 0.001°C. This inversion then provides a corrected dew point that incorporates the effects of the enhancement factor as well as differences between the ambient pressure and that in the housing.

For other instruments that measure vapor density, such as Lyman-alpha or tunable diode laser hygrometers, a similar conversion is made from vapor density to dew point, as documented below:

<sup>13</sup>prior to 2011 the conversion was made using the formula  $\text{DPxC} = 0.009109 + \text{DPx}(1.134055 + 0.001038\text{DPx})$ . For instruments producing measurements of vapor density (RHO), the previous Bulletin 9 section incorrectly gave the conversion formula as  $\text{DPxC} = 273.0Z/(22.51 - Z)$ , a conversion that would apply to frost point, not dew point. However, the code in use shows that the conversion was instead  $237.3Z/(17.27 - Z)$ , where  $Z$  in both cases is  $Z = \ln((\text{ATX} + 273.15)\text{RHO}/1322.3)$ .

DPx = uncorrected dew point measurement directly from an instrument, °C  
 RHO = water vapor density measurement directly from the instrument, g/m<sup>3</sup>  
 ATX = reference ambient temperature (°C)  
 $T_K$  = temperature in kelvin = ATX +  $T_0$   
 PSXC = reference ambient pressure (hPa) =  $p$   
 $e_t$  = intermediate vapor pressure used for calculation only  
 $M_w$  = molecular weight of water  
 $R_0$  = universal gas constant

for dew/frost point hygrometers, producing the measurement DPx: if DPx < 0°C:  
     obtain  $e_t$  from (12) using  $T_{FP} = \text{DPx} + T_0$   
 else (i.e., DPx ≥ 0°C):  
     obtain  $e_t$  from (13) using  $T_{DP} = \text{DPx} + T_0$   
 correct  $e_t$  for enhancement factor to get actual vapor pressure  $e$ :  
      $e = f(p, T_p) e_t$   
 obtain DPxC by finding the dew point corresponding to the vapor pressure  $e$ :  
     DPxC =  $F_{DP}(e)$

-----  
 for other instruments producing measurements of vapor density (RHO, g/m<sup>3</sup>):<sup>a</sup>  
 find the water vapor pressure in units of hPa:  
      $e = (\{\text{RHO}\} R_0 T_K / M_w) \times 10^{-5}$   
 find the equivalent dew point:  
     DPxC =  $F_{DP}(e)$

<sup>a</sup>prior to 2011 the following formula was used:

$$Z = \frac{\ln((\text{ATX} + 273.15) \text{RHO})}{1322.3}$$

$$\text{DPxC} = \frac{273.0Z}{(22.51 - Z)}$$

### Water Vapor Pressure (mb): EDPC

EDPC is the ambient vapor pressure of water, used in the calculation of several derived variables. It is usually obtained from a measurement of dew point, DPXC, which includes correction for the enhancement factor that influences dew point or frost point measurements.<sup>14</sup> The formula for obtaining the ambient water vapor pressure as a function of dew point is given in the discussion of DPxC in Section 4, Eqs. (13) and (14).

### Relative Humidity (per cent or Pa/hPa): RHUM

The relative humidity is the ratio of the water vapor pressure to the saturation water vapor

<sup>14</sup>prior to 2011, this variable was calculated using the Goff-Gratch formula. See the discussion of DPXC for more information on previous calculations.

pressure in equilibrium over a plane *liquid*-water surface, scaled to express the result in units of per cent:

EDPX = atmospheric water vapor pressure (mb)

ATX = ambient air temperature ( $^{\circ}\text{C}$ )

$e_s(\text{ATX})$  = saturation water vapor pressure at *dewpoint* ATX (mb)

(see eq. 13) for the formula used.)

$$\text{RHUM} = 100\% \times \frac{\{\text{EDPX}\}}{e_s(\{\text{ATX}\})} \quad (16)$$

To follow normal conventions, the change in saturation vapor pressure that arises from the enhancement factor is not included in the calculated relative humidity, even though the true relative humidity should include the enhancement factor as specified in (14) in the denominator of (16).

#### **Absolute Humidity, Water Vapor Density ( $\text{g}/\text{m}^3$ ): $\text{RHOx}$**

The absolute humidity is the water vapor density computed from various measurements of humidity as indicated by the 'x' suffix. The calculation proceeds in different ways for different sensors. For sensors that measure a chilled-mirror temperature, the calculation is based on the equation of state for a perfect gas and uses the water vapor pressure determined by the instrument, as in the following box.

ATX = ambient temperature ( $^{\circ}\text{C}$ )

EDPX = water vapor pressure, converted to consistent units

$C_{mb2Pa} = 100 \text{ Pa mb}^{-1}$  (conversion factor to MKS units)

$C_{kg2g} = 10^3 \text{ g kg}^{-1}$  (conversion factor to give final units of  $\text{g m}^{-3}$ )

$T_0 = 273.15 \text{ K}$

$$\text{RHOx} = C_{kg2g} \frac{C_{mb2Pa} \{\text{EDPx}\}}{R_w(\{\text{ATX}\} + T_0)} \quad (17)$$

$$= 216.674 \frac{\{\text{EDPx}\}}{(\{\text{ATX}\} + T_0)} \quad (18)$$

For instruments measuring the vapor pressure density (including the Lyman-alpha probes and the newer version called the UV hygrometer), the basic measurement from the instrument is the water vapor density, **RHOV** or **RHOLA**, determined by applying calibration coefficients to the measured signals (XUVI or VLA). In addition, a slow update to a dew-point measurement is used to compensate for drift in the calibration. The algorithm for the UV Hygrometer is as described in the following box; the processing used for early projects with the Lyman-alpha instruments is similar but more involved and won't be documented here because the instruments are obsolete. See RAF Bulletin 9 for the processing used for archived measurements from the Lyman-alpha hygrometers.

XUVI = output from the UV Hygrometer, after application of calibration coefficients  
 DPXC = corrected dewpoint from some preferred source, °C  
 ATX = preferred temperature, °C  
 RHODT = water vapor density determined by a chilled-mirror sensor  
 Tau = time constant for the exponential update (typically 300 s)

For valid measurements:<sup>a</sup>  
 Offset += (RHODT-XUVI-Offset)/Tau  
 RHOUV = XUVI + Offset

<sup>a</sup>defined by DPXC < ATX and valid numbers for XUVI and RHODT

### Specific Humidity (g/kg): SPHUM

The specific humidity is the mass of water vapor per unit mass of (moist) air, conventionally measured in g/kg.

PSXC = ambient pressure  
 EDPX = ambient water vapor pressure  
 $C_{kg2g} = 10^3 \text{ g kg}^{-1}$  (conversion factor to give final units of  $\text{g kg}^{-1}$ )

$$\text{SPHUM} = C_{kg2g} \frac{M_w}{M_d} \left( \frac{\{\text{EDPX}\}}{\{\text{PSXC}\} - \left(1 - \frac{M_w}{M_d}\right)\{\text{EDPX}\}} \right) \quad (19)$$

### Mixing Ratio (g/kg): MR, MRCR, MRLA, MRLA1, MRLH

The mixing ratio is the ratio of the mass of water to the mass of dry air, conventionally expressed in units of g/kg. Mixing ratios may be calculated for the various instruments measuring humidity on the aircraft, and the variable names reflect the source: MR from the dewpoint hygrometers, MRCR from the cryogenic hygrometer, MRLA from the Lyman-alpha sensor, MRLA1 if there is a second Lyman-alpha sensor, and MRLH from a laser hygrometer. The example in the box below is for the case of the dewpoint hygrometers; others are analogous.

EDPX = water vapor pressure (mb)  
 PSXC = ambient total pressure  
 $C_{2kg2g} = 10^3 \text{ g kg}^{-1}$  (conversion factor to give final units of  $\text{g kg}^{-1}$ )

$$\text{MR} = C_{kg2g} \frac{M_w}{M_d} \frac{\{\text{EDPX}\}}{(\{\text{PSXC}\} - \{\text{EDPX}\})} \quad (20)$$



**Potential Temperature (K): THETA**

The potential temperature in the output data files is the temperature reached if a dry parcel at the measured pressure and temperature would be compressed or expanded adiabatically to a pressure of 1000 mb. It does not take into account the difference in specific heats caused by the presence of water vapor, and water vapor can change the exponent in the formula below enough to produce errors of 1 K or more.

ATX = ambient temperature, °C

PSXC = ambient pressure (mb)

$p_0$  = reference pressure = 1000 mb

$R_d$  = gas constant for dry air

$c_{pd}$  = specific heat at constant pressure for dry air

$$\text{THETA} = (\{ \text{ATX} \} + T_0) \left( \frac{p_0}{\{ \text{PSXC} \}} \right)^{R_d/c_{pd}} \quad (21)$$

**Pseudo-Adiabatic Equivalent Potential Temperature (K): THETA\_E**

changed 201

Beginning in 2011, pseudo-adiabatic equivalent potential temperature is calculated using the method developed by Davies-Jones (2009).<sup>15</sup> His formula is

$$\Theta_E = \Theta_{DL} \exp \left\{ \frac{r(L_0^* - L_1^*(T_L - T_0) + K_2 r)}{c_{pd} T_L} \right\} \quad (22)$$

and

$$\Theta_{DL} = T_K \left( \frac{p_0}{p_d} \right)^{0.2854} \left( \frac{T_K}{T_L} \right)^{0.28 \times 10^{-3} r} \quad (23)$$

where  $T_K$  is the absolute temperature (in kelvin) at the measurement level,  $p_d$  is the partial pressure of dry air at that level,  $p_0$  is the reference pressure (conventionally 1000 hPa),  $r$  is the (dimensionless) water vapor mixing ratio,  $c_{pd}$  the specific heat of dry air,  $T_L$  the temperature at the lifted condensation level (in kelvin), and  $T_0 = 273.15$  K. The coefficients in this formula are:  $L_0 = 2.56313 \times 10^6 \text{ J kg}^{-1}$ ,  $L_1 = 1754 \text{ J kg}^{-1} \text{ K}^{-1}$ , and  $K_2 = 1.137 \times 10^6 \text{ J kg}^{-1}$ . The asterisks on  $L_0^*$  and  $L_1^*$  indicate that these coefficients depart from the best estimate of the coefficients that give the latent heat of vaporization of water, but they have been adjusted to optimize the fit to values obtained by exact integration. Note that, unlike the formula discussed below that was used prior to 2011, the mixing ratio must be used in dimensionless form (i.e., kg/kg), *not* with units of g/kg. The following empirical formula, developed by Bolton (1980),<sup>16</sup> is used to determine  $T_L$ :

$$T_L = \frac{\beta_1}{3.5 \ln(T_K/\beta_3) - \ln(e/\beta_4) + \beta_5} + \beta_2 \quad (24)$$

<sup>15</sup>Davies-Jones, R., 2009: On formulas for equivalent potential temperature. *Mon. Wea. Review*, **137**, 3137–3148.

<sup>16</sup>Bolton, D., 1980: The computation of equivalent potential temperature. *Mon. Wea. Rev.*, **108**, 1046–1053.

where  $e$  is the water vapor pressure,  $\beta_1 = 2840 \text{ K}$ ,  $\beta_2 = 55 \text{ K}$ ,  $\beta_3 = 1 \text{ K}$ ,  $\beta_4 = 1 \text{ hPa}$ ,  $\beta_5 = -4.805$ . (Coefficients  $\beta_3$  and  $\beta_4$  have been introduced into (24) only to ensure that arguments to logarithms are dimensionless and to specify the units that must be used to achieve that.)

Prior to 2011, the variable called the equivalent potential temperature<sup>17</sup> in the output data files was that obtained using the method of Bolton (1980), which used the same formula to obtain the temperature at the lifted condensation level ( $T_L$ ) and then used that temperature to find the value of potential temperature of dry air that would result if the parcel were lifted from that point until all water vapor condensed and was removed from the air parcel. The formulas used were as follows:

$T_L$ = temperature at the lifted condensation level, K ATX = ambient temperature ( $^{\circ}\text{C}$ ) EDPX = water vapor pressure (mb) MR = mixing ratio (g/kg) THETA = potential temperature (K)
$T_L = \frac{2840.}{3.5 \ln(\{\text{ATX}\} + T_0) - \ln(\{\text{EDPX}\}) - 4.805} + 55.$ $\text{THETA}_E = \{\text{THETA}\} \left( \frac{3.376}{T_L} - 0.00254 \right) (\{\text{MR}\})(1 + 0.00081(\{\text{MR}\})) \quad (25)$

Differences vs the new formula are usually minor but can be of order 0.5 K.

### Virtual Temperature ( $^{\circ}\text{C}$ ): TVIR

The virtual temperature is the temperature of dry air having the same pressure and density as the air being sampled, and so adjusts for the buoyancy added by water vapor.

ATX = ambient temperature, $^{\circ}\text{C}$ $r$ = mixing ratio, dimensionless [kg/kg] = $\{\text{MR}\}/(1000 \text{ g/kg})$ $T_0 = 273.15 \text{ K}$
$\text{TVIR} = (\{\text{ATX}\} + T_0) \left( \frac{1 + \frac{M_d}{M_w} r}{1 + r} \right) - T_0 \quad (26)$

<sup>17</sup>The AMS glossary defines equivalent potential temperature as applying to the adiabatic process, not the pseudo-adiabatic process; the name of this variable has therefore been changed.

**Virtual Potential Temperature (K): THETAV**

The virtual potential temperature is analogous to the potential temperature except that it is based on the virtual temperature (TVIR) instead of the ambient temperature (ATX). Dry-adiabatic expansion or compression to the reference level (1000 hPa) is assumed. As for THETA, use of dry-air values for the gas constant and specific heat at constant pressure can lead to significant errors in humid conditions. For further information, see this note. (XXX reference needed)

TVIR = virtual temperature, °C

PSXC = ambient pressure, hPa

$R_d$  = gas constant for dry air

$c_{pd}$  = specific heat at constant pressure for dry air (taken to be exactly  $7R_d/2$ )

$T_0 = 273.15$  K

$p_0$  = reference pressure, conventionally 1000 hPa

$$\text{THETAV} = (\{\text{TVIR}\} + T_0) \left( \frac{p_0}{\{\text{PSXC}\}} \right)^{R_d/c_{pd}} \quad (27)$$

**Cryogenic Hygrometer Inlet Pressure (mb) and Frost Point Temperature (°C): CRHP and VCRH (obsolete)**

These are measurements made directly in the chamber of the cryogenic hygrometer, a cabin-mounted instrument connected to outside air by an inlet line. CRHP is the pressure and VCRH is the frost-point temperature measured inside that chamber. VCRH is determined from a third-order calibration equation applied to the voltage measured by the instrument.

**Corrected Cryogenic Frost Point Temperature and Dew Point Temperature (°C): FPCRC and DPCRC (obsolete)**

This is an obsolete instrument but its description is included here because these variables appear in some old data files. To obtain estimates of the ambient frost point and dew point, the measurements made inside the chamber of the cryogenic hygrometer (CVRH and CRHP) must be corrected for the difference in water vapor pressure between that chamber and ambient conditions. The ratio of the chamber pressure to the ambient pressure is assumed to be the same as the ratio of the chamber vapor pressure to the ambient vapor pressure. The vapor pressure in the chamber is determined from the Goff-Gratch (1946) equation<sup>18</sup> for saturation vapor pressure with respect to a plane ice surface. This vapor pressure is then used with CRHP and a measure of the ambient pressure (PSXC) to determine the vapor pressure in the outside air, and this is converted to an equivalent dew-point in the same manner as for the standard variables DPxC. The instrument is only used for measurements of frost point less than  $-15^\circ\text{C}$  because it does not function well above that frost point. The steps are documented below:

<sup>18</sup>Goff, J. A., and S. Gratch (1946) Low-pressure properties of water from  $-160$  to  $212^\circ\text{F}$ , referenced and used in the Smithsonian Tables (List, 1980).

VCRH = frost point inside the cryogenic hygrometer ( $^{\circ}\text{C}$ )  
 CRHP = pressure inside the chamber of the cryogenic hygrometer (mb)  
 PSXC = reference ambient pressure (mb)  
 $f_i$  = enhancement factor (see Appendix C of Bulletin 9)  
 $F_1(T_d)$  = Goff-Gratch formula for vapor pressure at dew point  $T_d$   
 $F_2(T_f)$  = Goff-Gratch formula for vapor pressure at frost point  $T_f$   
 $T_3$  = temperature at the triple point of water = 273.16 K

chamber vapor pressure  $e_{ic}$  (mb):

$$e_{ic} = (6.1071 \text{ mb}) \times 10^A$$

$$\begin{aligned} \text{where } A = & -9.09718 \left( \frac{T_3}{\text{VCRH} + T_3} - 1 \right) \\ & + 3.56654 \log_{10} \left( \frac{T_3}{\text{VCRH} + T_3} \right) \\ & + 0.876793 \left( 1 - \frac{\text{VCRH} + T_3}{T_3} \right) \end{aligned}$$

ambient vapor pressure  $e_a$  (mb):

$$e_a = e_{ic} \left( \frac{\text{PSXC}}{\text{CRHP}} \right) f_i$$

ambient dew and frost point DPCRC and FPCRC: (iterative solution)

$$\begin{aligned} e_a &= F_1(\text{DPCRC}) \\ &= F_2(\text{FPCRC}) \end{aligned}$$

#### **Voltage Output From the Lyman-alpha Sensor (V): VLA, VLA1 (obsolete)**

This variable is the voltage output from the Lyman-alpha absorption hygrometer, which provides fast-response, high-resolution measurements of water vapor density. (If a second sensor is used, a 1 is added to the variable name associated with the second sensor.)

#### **Voltage Output from the UV Hygrometer (V): XUVI**

The UV Hygrometer is a modern (as of 2009) version of the Lyman-alpha hygrometer, which provides a signal that represents water vapor density. The instrument also provides measurements of pressure and temperature inside the sensing cavity; they are, respectively, **XUVP** and **XUVT**.

**Calculated Surface Pressure (mb): PSURF**

The estimated surface pressure is calculated from HGM (a radar-altimeter measurement of height), TVIR, PSXC, and MR using the thickness equation. The average temperature for the layer is obtained by using HGM and assuming a dry-adiabatic lapse rate from the flight level to the surface. Because of this assumption, the result is only valid for flight in a well-mixed surface layer or in other conditions in which the temperature lapse rate matches the dry-adiabatic lapse rate.

PSXC = ambient pressure (hPa)

HGM = (radar) altitude above the surface (m)

TVIR = virtual temperature ( $^{\circ}\text{C}$ )

PSURF = estimated surface pressure (hPa)

$g$  = acceleration of gravity

$R_d$  = gas constant for dry air

$c_{pd}$  = specific heat of dry air at constant pressure

$$T_m = (\{\text{TVIR}\} + T_0) + 0.5\{\text{HGM}\} \frac{g}{c_{pd}}$$

$$\text{PSURF} = \{\text{PSXC}\} \exp \left\{ \frac{g \{\text{HGM}\}}{R_d T_m} \right\} \quad (28)$$

## 5 WIND

RAF Bulletin 23 documents the calculation of wind components, both with respect to the earth (UI, VI, WI, WS and WD) and with respect to the aircraft (UX and VY). In data processing, a separate function (GUSTO in GENPRO, gust in NIMBUS) is used to derive these wind components. That function uses the Inertial Reference Unit (IRU) measurements as well as aircraft true airspeed, aircraft angle of attack, and aircraft sideslip angle. The wind components calculated in GUSTO/gust are used to derive the wind direction (WD) and wind speed (WS). Additional variables UIC, VIC, WSC, WDC, UXC, and VYC are also calculated based on the variables VNSC, VEWC discussed in section 3.4, which combine IRU and GPS information to obtain improved measurements of the aircraft motion that combine the high-frequency response of the IRU measurements with the long-term accuracy of the GPS measurements.

The details contained in Bulletin 23 will not be repeated here; the description there still describes the wind calculations in use, so please consult that bulletin for the processing algorithms. The variables pertaining to the relative wind are described in the next subsection, and the variables characterizing the wind are then described briefly in the last subsection. Some additional detail is included in cases where procedures are not documented in that earlier bulletin.

### 5.1 Relative Wind

Wind is measured by adding two vectors: (1) the measured air motion relative to the aircraft (called the relative wind), and (2) the motion of the aircraft relative to the Earth. The following are the measurements used to determine the relative wind. The motion of the aircraft relative to the ground is discussed in the next section, and the combination of these two vectors to measure the wind is described in RAF Bulletin 23. The radome gust-sensing system is discussed briefly on page 31.

#### **Dynamic Pressure (mb): QCx, QCxC**

Dynamic pressure is the difference between the pitot (total) pressure resulting from the flight speed of the aircraft and the static pressure that would be present in the absence of motion. The QCxC value is corrected for local flow-field distortion, as described in RAF Bulletin 21. A Rosemount Model 1221 differential pressure transducer is used for all measurements of dynamic pressure. This measurement enters the calculation of true airspeed and Mach number and so is needed to calculate many derived variables.

#### **Aircraft True Airspeed (m/s): TASx**

This derived measurement of the flight speed of the aircraft relative to the atmosphere is based on the Mach number calculated from both the dynamic pressure at location x and the static pressure. See the derivation for ATx on page 32. The different variables for TASx (TASF, TASR, etc) use different measurements of QCxC in the calculation of Mach number.

(see box for ATx and MACHx)

Note dependence of MACHx on choices for QCxC and PSXC

TASx depends on QCxC, PSXC, ATX

where PSXC and ATX are the preferred choices

$$TASx = \{MACHx\} \sqrt{\gamma R_d (\{ATX\} + T_0)} \quad (29)$$

### Aircraft True Airspeed (Humidity Corrected) (m/s): **TASHC**

This derived measurement of true airspeed takes into account the deviations of the specific heats of moist air from those of dry air. See List, 1971, pp 295, 331-339, and Khelif, et al., 1999. The present form of this equation, from Khelif et al. 1999<sup>19</sup>, adds a moisture correction to a true airspeed derived for dry air:

SPHUM = specific humidity, g/kg

$$TASHC = TASX * (1.0 + 0.000304 * SPHUM)$$

### Attack Angle Differential Pressure (mb): **ADIFR**<sup>20</sup>

This variable records the pressure difference between the top and bottom pressure ports of the radome gust-sensing system.

### Sideslip Angle Differential Pressure (mb): **BDIFR**<sup>21</sup>

This variable records the pressure difference between starboard and port pressure inlets of the radome gust-sensing system, in the horizontal plane of the aircraft's flow-angle sensor system.

### Attack Angle, Radome (°): **AKRD**

This derived output represents the angle of attack of the aircraft. It is obtained from ADIFR and a dynamic pressure using a sensitivity function that has been determined empirically for each aircraft.

<sup>19</sup>Khelif, D., S.P. Burns, and C.A. Friehe, 1999: Improved wind measurements on research aircraft. *Journal of Atmospheric and Oceanic Technology*, **16**, 860-875.

<sup>20</sup>

Obsolete variable **ADIF** is a similar variable used for old gust-boom systems or for Rosemount Model 858AJ flow-angle sensors.

<sup>21</sup>

Obsolete variable **BDIF** is a similar variable used for old gust-boom systems or for Rosemount Model 858AJ flow-angle sensors.

ADIFR = attack differential pressure, radome  
 QCXC = reference dynamic pressure  
 XMACH2 = square of the Mach number  
 $c_0, c_1$  = sensitivity coefficients determined empirically  
 = {0.3843, (1/0.06653) °} for the C-130  
 = {0.2571, (1/0.04724) °} for the GV  
 $c_3, c_4$  = additional coefficients for the GV  
 = {0.6195°, -1.02758°} for XMACH2 > 0.194  
 = {0.42°, 0} for XMACH2 ≤ 0.194

For the C-130:

$$AKRD = c_1 \left( \frac{\{ADIFR\}}{\{QCXC\}} + c_0 \right)$$

For the GV:

$$AKRD = c_1 \left( \frac{\{ADIFR\}}{\{QCXC\}} + c_0 \right) + c_3 + c_4 \{XMACH2\}$$

### Reference Attack Angle (°): ATTACK

This variable is the reference selected from other measurements of angle of attack in the data set. In most projects, it is equal to AKRD. It is used where attack angle is needed for other derived calculations (e.g., wind measurements).

### Sideslip Angle (Differential Pressure) (°): SSRD

This variable is derived from BDIFR and a dynamic pressure using a sensitivity function that has been determined empirically for each aircraft.

BDIFR = differential pressure between sideslip pressure ports, radome (mb)  
 QCXC = dynamic pressure (mb)  
 $b_0, b_1$  = empirical coefficients dependent on the aircraft and radome configuration  
 = {-0.000983, (1/0.09189)°} for the C-130  
 \_\_\_\_\_ = {-0.0023, (1/0.04727)°} for the GV

$$SSRD = b_1 \left( \frac{\{BDIFR\}}{\{QCXC\}} - b_0 \right)$$

### Reference Sideslip Angle (°): SSLIP

This variable is the reference selected from other measurements of sideslip angle in the data set. In most projects, it is equal to SSRD. It is used where sideslip angle is needed for other derived calculations (e.g., wind measurements).



## 5.2 Wind Components and the Wind Vector

**Wind Vector East Component (m/s): UI**

**Wind Vector North Component (m/s): VI**

**Wind Vector Vertical Gust Component (m/s): WI**

These measurements comprise the three-dimensional wind vector with respect to the earth. UI is the east-west component with positive values toward the east, VI is the north-south component with positive values toward the north, and WI is the vertical component with positive values toward the zenith.

**Wind Speed (m/s): WS**

**Wind Direction (°): WD**

These variables are obtained in a straightforward manner from UI and VI. The resulting wind direction is relative to true north.

UI = easterly component of the horizontal wind

VI = northerly component of the horizontal wind

atan2 = 4-quadrant arc-tangent function producing output in radians from  $-\pi$  to  $\pi$

$C_{rd}$  = conversion factor, radians to degrees,  $= 180/\pi$  [units:  $^{\circ}/radian$ ]

$$\begin{aligned} WS &= \sqrt{\{UI\}^2 + \{VI\}^2} \\ WD &= C_{rd} \operatorname{atan2}(\{UI\}, \{VI\}) + 180^{\circ} \end{aligned} \quad (30)$$

**Wind Vector Longitudinal Component (m/s): UX**

**Wind Vector Lateral Component (m/s): VY**

These measurements represent the horizontal wind vector relative to the frame of reference attached to the aircraft and moving with the aircraft. UX is parallel to the longitudinal axis, and positive is toward the nose. VY is the component normal to the longitudinal axis; positive is toward the port (or left) wing.

**GPS-Corrected Wind Vector, East Component (m/s): UIC**

**GPS-Corrected Wind Vector, North Component (m/s): VIC**

These measurements give the horizontal wind components respectively toward the east and toward the north. They are derived from measurements from an inertial reference unit (IRU) and a Global Positioning System (GPS), as described in the discussion of VEW and VNS above. They are calculated just as for UX and VY except that the GPS-corrected values for the aircraft groundspeed are used in place of the IRU-based values. They are considered “corrected” from the original measurements from the IRU or GPS, as described in section 3.4.

**Wind Vector, Vertical Component (m/s): WIC**

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This is the standard calculation of vertical wind.<sup>22</sup> It is based on measurements from the IRU, including the measurement VSPD that is the direct measurement of vertical speed of the aircraft as discussed in section 3. This should be used in preference to WI if the latter is present; see the discussion of WP3 in section 3. Positive values are toward the zenith.

**GPS-Corrected Wind Speed (m/s): WSC****GPS-Corrected Wind Direction (°): WDC**

These variables are obtained in a straightforward manner from UIC and VIC, using equations analogous to (30) but with UIC and VIC as input measurements. They are expected to be the best measurements of wind because they combine the best features of the IRU and GPS measurements.

**GPS-Corrected Wind Vector, Longitudinal Component (m/s): UXC****GPS-Corrected Wind Vector, Lateral Component (m/s): VYC**

These measurements give the longitudinal and lateral components of the three-dimensional wind, similar to UX and VY, but corrected by the complementary-filter algorithm that combines IRU and GPS measurements, as discussed in Section 3.4. The components UXC and VYC are toward the front of the aircraft and toward the port (left) wing, respectively.

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<sup>22</sup>This variable is named “GPS-Corrected Wind Vector” in some output prior to 2011, but that name was incorrect because the algorithm does not involve measurements from a GPS.

## 6 CLOUD PHYSICS VARIABLES

### 6.1 Measurements of Liquid Water Content

#### **Raw Output PMS/CSIRO (KING) Liquid Water Content (W): PLWC, PLWC1**

This variable is the output of a PMS/CSIRO (King) liquid water probe (in watts). PLWC is the power required to maintain constant temperature in a heated element as that element is cooled by convection and evaporation of impinging liquid water. The convective heat losses are determined by calibration in dry air over a range of airspeeds and temperatures, so that the remaining power can be related to the liquid water content. The instrument is described in RAF Bulletin 24. See PLWCC (which follows) for processing.

#### **Corrected PMS/CSIRO (KING) Liquid Water Content ( $\text{g/m}^3$ ): PLWCC, PLWCC1**

This is the corrected liquid water content obtained from relating the power consumption required to maintain a constant temperature to the liquid water content, taking into account the effect of convective heat losses. The instrument and processing are described by King et al. (1978)<sup>23</sup> and in a note available at this URL: XXX. Because the temperature of the sensing wire is typically well above the boiling point of water, the assumption made in processing is that the water collected on the sensing wire is vaporized at the boiling point  $T_b$ . The boiling point is represented as a function of pressure as described below. change 2011

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<sup>23</sup>King, W. D., D. A. Parkin and R. J. Handsworth, 1978 A hot-wire liquid water device having fully calculable response characteristics. J. Appl. Meteorol., 17, 1809–1813. See also Bradley, S. G., and W. D. King, 1979 Frequency response of the CSIRO Liquid Water Probe. J. Appl. Meteorol., 18, 361–366.

PLWC = total power dissipated by the probe (W)  
 $P_D$  = power dissipated by the cooling effect of dry air alone  
 $P_W$  = power needed to heat and vaporize the liquid water that hits the probe element  
 $L$  = length of the probe sensitive element, typically 0.021 m  
 $d$  = diameter of the probe sensitive element, typically  $1.805 \times 10^{-3}$  m  
 $T_s$  = sensor temperature (K)  
 $T_a$  = ambient temperature (K) = ATX+273.15  
 $T_b$  = boiling temperature of water (dependent on pressure):  
     with  $x = \log_{10}(p/(1\text{hPa}))$  and  $B = 1^\circ\text{C}$ ,  $T_b = B \times 10^{(b_0+b_1x+b_2x^2+b_3x^3)}$   
 $T_m = (T_a + T_s)/2$  = mean temperature for air properties  
 $L_v(T_b)$  = latent heat of vaporization of water =  $(2.501+0.00237(T_a - T_0)) \times 10^6 \text{ J kg}^{-1}$   
 $c_w$  = specific heat of water =  $1875 \text{ J kg}^{-1} \text{ K}^{-1}$   
 $U_a$  = true airspeed (m/s) = TASX  
 $\lambda_c$  = thermal conductivity of dry air  $(2.38+0.0071(T_m - T_0)) \times 10^{-2} \text{ J m}^{-1} \text{ s}^{-1} \text{ K}^{-1}$   
 $\mu$  = viscosity of air =  $(1.718+0.0049(T_m - T_0)) \times 10^{-5} \text{ kg m}^{-1} \text{ s}^{-1}$   
 $\rho_a$  = density of air =  $p/(R_d T_a)$   
 $\text{Re}$  = Reynolds number =  $\rho_a U_a d / \mu_a$   
 $\text{Nu}$  = Nusselt Number relating conduction heat loss to the total heat loss for dry air:  
     typically  $\text{Nu} = a_0 \text{Re}^{a_1}$   
 $C_{kg2g} = 1000$  = grams per kilogram  
     (unit conversion to conventional units for liquid water content)  
 $\chi$  = liquid water content ( $\text{g/m}^3$ ) = PLWCC

$$\text{PLWC} = P_D + P_W$$

where

$$P_D = \pi \text{Nu} L \lambda_c (T_s - T_a)$$

$$P_W = L d [L_v(T_b) + c_w (T_b - T_a)] U_a \chi$$

Result:

$$\text{PLWCC} = \chi = \frac{C_{kg2g} (\{\text{PLWC}\} - P_D)}{L d U_a [L_v(T_b) + c_w (T_b - T_a)]}$$

### Raw Output Rosemount Icing Detector (V): RICE

A Rosemount 871F ice-accretion probe consists of a rod set in vibration by a piezoelectric crystal. The oscillation frequency of the probe changes with ice loading, so in supercooled cloud ice accumulates on the sensor, and the change in oscillation frequency is transmitted as a DC voltage.. When the probe loads to a trigger point, the probe heats the rod to remove the ice. Its output voltage is a measure of the mass of the accreted ice. The rate of voltage change is converted to an estimate of the supercooled liquid water content, as described in the next paragraph.

**Derived Supercooled Liquid Water Content ( $\text{g/m}^3$ ): SCLWC** {obsolete? Couldn't find code}

This variable is the supercooled liquid water content obtained from the change in accreted mass on the Rosemount 871F ice-accretion probe over one second. Note that the output is not valid during the probe deicing cycle. This cycle is apparent in the RICE output (a peak followed by a decrease to near zero). Supercooled liquid water content is determined by first calculating a water drop impingement rate which is a function of the effective surface area, the collection efficiency, the true airspeed, and the supercooled liquid water content. The impingement rate obtained is equated to the accreted mass of ice collected by the probe in one second (empirical voltage/mass relationship). The resulting equation is solved for supercooled water content.

$A$  = effective surface area of the probe ( $\text{m}^2$ )

$\Delta t$  = time interval during which an increment of mass accretes (s)

$\Delta m$  = mass of ice accreted on the probe in the time interval  $\Delta t$  (g)

$U_a$  = true airspeed (m/s)

$$\text{SCLWC} = AU_a \frac{\Delta m}{\Delta t}$$

## 6.2 Sensors of Individual Particles (1-D Probes)

The RAF operates a set of hydrometeor detectors that provide single-dimension measurements (i.e., not images) of individual particle sizes. RAF Bulletin 24 contains extensive information on the operating principles and characteristics of some of the older instruments. Here the focus will be on the meanings of the variables in the archived data files.

Four- and five-character variable names shown in this section are generic. The actual names appearing in NIMBUS-generated production output data sets have appended to them an underscore (\_) and three more characters which indicate a probe's specific aircraft mounting location. For example, AFSSP\_RPI is the Total Accumulation from an FSSP-100 probe mounted on the inboard, right-side pod. The codes presently in use are given in the following table. For the GV, there are 12 locations available, characterized by three letters. The first is the wing ({L,R} for {port,starboard}), the second is the pylon ({I,M,O} for inboard, middle, outboard)), the third is which of the two possible canister locations at the pylon is used ({I,O} for {inboard, outboard})).

Code	Location	Aircraft
OBL	Outboard Left	C-130Q
IBL	Inboard Left	C-130Q
OBR	Outboard Right	C-130Q
IBR	Inboard Right	C-130Q
LPO	Left Pod Outboard	C-130Q
LPI	Left Pod Inboard	C-130Q
LPC	Left Pod Center	C-130Q
RPO	Right Pod Outboard	C-130Q
RPI	Right Pod Inboard	C-130Q
RPC	Right Pod Center	C-130Q
OBL	Left Wing	Electra
IBL	Left Pylon	Electra
WDL	Window Left	Electra
OBR	Right Wing	Electra
IBR	Right Pylon	Electra
WDR	Window Right	Electra
{L,R}{I,M,O}{I,O}	see discussion above	GV

The probe type also is coded into each variable's name, sometimes using four characters, sometimes only one: FSSP-100 (FSSP or F), FSSP-300 (F300 or 3), CDP (CDP or D), UHSAS (UHSAS or U), PCAS (PCAS or P), OAP-200X (200X or X), OAP-260X (260X or 6) and OAP-200Y (200Y or Y). Prefix letters are used to identify the type of measurement (A=accumulated particle counts per time interval per channel, C = concentration per channel, CONC = Concentration from all channels, DBAR = Mean Diameter, DISP = Dispersion, PLWC = Liquid Water Content, DBZ = Radar Reflectivity Factor).

Generic Name		Probe	Channels	Usable	Diameter Range	Bin Width
FSSP	F	FSSP-100	0-15	1-16	(See FRNG below)	
UHSAS	U	UHSAS	0-63	??		
CDP	D	CDP				
F300	3	FSSP-300	0-31	1-31	0.3–20.0 $\mu m$	variable
PCAS	P	PCAS	0-15	1-15	0.1–3.0 $\mu m$	variable
200X	X	OAP-200X	0-15	1-15	40–280 $\mu m$	10 $\mu m$
260X	6	OAP-260X	0-63	3-62	40-620 $\mu m$	10 $\mu m$
200Y	Y	OAP-200Y	0-15	1-15	300–4500 $\mu m$	300 $\mu m$

**Total Accumulation (counts per time interval):**

**AFSSP, AF300, APCAS, A200X, A260X, A200Y, ACDP, AUHSAS**

This measurement is the total number of particles detected by a PMS-1D probe per unit time. These measurements have “vector” character in the NetCDF output files, with dimension equal to the number of usable channels in the table above and one entry per channel.

**Concentration (per channel) ( $cm^{-3}$ ):** CFSSP, CF300, CPCAS, CCDP, CUHSAS

**Concentration (per channel) ( $liter^{-1}$ ):** C200X, C260X, C200Y

These measurements give the particle concentrations in each usable bin of the probe. They have “vector” character is the NETCDF output files, with dimension equal to the number of usable channels in the table above and with one entry per channel. For the scattering spectrometer probes (FSSP-100, FSSP-300, PCAS, CDP, UHSAS) the concentration value is modified by the probe activity (FACT, PACT) as described below. The concentration is obtained from the total number of particles detected and a calculated, probe-dependent sample volume. For details, see RAF Bulletin 24.

**Concentration, sum over all channels ( $cm^{-3}$ ):** CONCF, CONC3, CONCP, CONCD, CONCU

**Concentration, sum over all channels ( $liter^{-1}$ ):** CONCX, CONC6, CONCY

These measurements are the particle concentrations summed over all channels to give the total particle concentration in the size range of the probe. For details, see RAF Bulletin 24.

**Mean Diameter ( $\mu m$ ):** DBARF, DBAR3, DBARP, DBARX, DBAR6, DBARY, DBARD, DBARU

The mean diameter is the arithmetic average of all particle diameters. It is calculated as follows:

$\{Cy_i\}$  = concentration from probe y in channel i

(e.g., y=FSSP to calculate DBARF)

i1 = lowest usable channel for the probe

i2 = highest usable channel for the probe

$d_i$  = mean diameter of particles in channel i for this probe ( $\mu m$ )

$$DBAR_x = \frac{\sum_{i=i1}^{i2} \{Cy_i\} d_i}{\sum_{i=i1}^{i2} \{Cy_i\}}$$

**Dispersion (dimensionless):** DISPF, DISP3, DISPP, DISPX, DISP6, DISPY, DISPD, DISPU

The dispersion is the ratio of the standard deviation of particle diameters to the mean particle diameter.

$\{\text{DBAR}_x\}$  = mean particle diameter ( $\mu m$ )  
 $\{C_{y_i}\}$  = concentration from probe y in channel i  
 (e.g., y=FSSP to calculate DISPF)  
 $d_i$  = diameter measured in channel i of probe y  
 $i1$  = lowest usable channel for the probe  
 $i2$  = highest usable channel for the probe

$$\text{DISP}_x = \frac{1}{\{\text{DBAR}_x\}} \left\{ \frac{\sum_{i=i1}^{i2} \{C_{y_i}\} d_i^2}{\sum_{i=i1}^{i2} \{C_{y_i}\}} - \{\text{DBAR}_x\}^2 \right\}^{1/2}$$

### Liquid/Ice Water Content ( $g/m^3$ ):

#### **PLWCF, PLWCX, PLWC6, PLWCY, PLWCD**

These variables are derived from the measured concentration ( $\text{CONC}_x$ ) and the third moment of the equivalent droplet diameter. The equivalent droplet diameter is the diameter that represents the mass in the detected particle. The equivalent droplet diameter is normally the measured diameter for liquid hydrometeors, but some processing has used other assumptions and this is a choice that can be made based on project needs. Using this definition allows for the approximate estimation of ice water content in cases where it is known that all hydrometeors are ice.

:

$d_{e,i}$  = equivalent melted diameter for channel i of probe x  
 $\{C_{y_i}\}$  = concentration from probe y in channel i  
 (e.g., y=FSSP to calculate  $\text{DISP}_x$  for x=F)  
 $\rho_w$  = density of water ( $10^3 kg/m^3$ )  
 $i1$  = lowest usable channel for the probe  
 $i2$  = highest usable channel for the probe

$$\text{PLWC}_x = \frac{\pi \rho_w}{6} \sum_{i=i1}^{i2} \{C_{y_i}\} d_{e,i}^3$$

(units and a scale factor are selected so that the output variable is in units of  $g/m^3$ )

### **Radar Reflectivity Factor (dbZ): DBZF, DBZX, DBZ6, DBZY, DBZD**

The radar reflectivity factor for water is a measure of the product of the concentration and the sixth moment of the droplet diameter. An equivalent radar reflectivity factor can be calculated from the hydrometeor size distribution if an assumption about composition of the particles is made, but this variable is not part of normal data files. The radar reflectivity factor is a characteristic only of the hydrometeor size distribution; it is *not* a measure of radar reflectivity, because the latter also depends on wavelength, dielectric constant, and



other characteristics of the hydrometeors. The normally used radar reflectivity factor is measured on a logarithmic scale that depends on a particular choice of units, so (although it is not conventionally included) an appropriate scale factor  $Z_r$  is included in the following equation to satisfy the convention that arguments of logarithms should be dimensionless.

$d_i$  = diameter for channel  $i$  of probe  $x$   
 $\{Cy_i\}$  = concentration from probe  $y$  in channel  $i$   
 (e.g.,  $y$ =FSSP to calculate DISPx for  $x$ =F)  
 $i1$  = lowest usable channel for the probe  
 $i2$  = highest usable channel for the probe  
 $Z_r$  = reference factor for units =  $1 \text{ mm}^6/\text{m}^3$

$$\text{DBZ}_x = 10 \log_{10} \left( \frac{1}{Z_r} \sum_{i=i1}^{i2} \{Cy_i\} d_i^6 \right)$$

**FSSP-100 Range (dimensionless): FRNG, FRANGE**

This variable records the size range in use for the FSSP-100 probe

Range	Nominal Size Range	Nominal Bin Width
0	2–47 $\mu\text{m}$	3 $\mu\text{m}$
1	2–32 $\mu\text{m}$	2 $\mu\text{m}$
2	1–15 $\mu\text{m}$	1 $\mu\text{m}$
3	0.5–7.5 $\mu\text{m}$	0.5 $\mu\text{m}$

In recent NETCDF data files, the actual bin boundaries used for processing are recorded in the header. That header should be consulted because processing sometimes uses non-standard sizes selected to adjust for Mie scattering, which causes departures from the nominal linear bins.

**FSSP-100 Fast Resets (number per sample interval): FRST, FRESET**

The FSSP records events called “fast resets” that occur when a particle traverses the beam outside the depth-of-field and therefore is not accepted for sizing. To avoid the processing time associated with sizing, the probe resets quickly in this case, but there is still some dead time when the probe cannot record another event. Fast resets consume a time determined by circuit characteristics, so that time is determined in laboratory tests of the FSSP circuitry. This variable is needed in addition to the “Total Stobes” to determine what fraction of the time the probe is unable to accept another particle, and this “dead time” enters calculation of the concentration.

**FSSP-100 Total Stobes (number per sample interval): FSTB, FSTROB**

A “strobe” is generated in the FSSP whenever a particle is detected within its depth-of-field. Not all such particles are accepted for inclusion in the size distribution, however, because some pass through the outer regions of the illuminating laser beam and therefore produce shorter and smaller-amplitude pulses than those passing through the center of the

beam. The probe maintains a running estimate of the average transit time and rejects particles with transit times shorter than this average. The total number of strobes recorded is therefore more than the number of sized particles, and the ratio of strobes to accepted particles can indicate quality of operation of the probe. Also, the strobes require processing and so contribute to the dead time of the probe, affecting the concentration unless a correction is made. See RAF Bulletin 24 for more discussion on the operation of the FSSP.

#### **FSSP-100 Beam Fraction (dimensionless): FBMFR**

This variable records the ratio of the number of velocity-accepted particles (particles that pass through the effective beam diameter) to the total number of particles detected in the depth-of-field of the beam (the total strobes). See the discussion of Total Strobes for more information.

AFSSP = valid particles sized per sample interval  
 FSTROB = strobes generated by particles in the depth-of-field,  
 per sample interval

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$$FBMFR = \{AFSSP\} / \{FSTROB\}$$

#### **FSSP-100 Calculated Activity Fraction (dimensionless): FACT**

This variable represents the fraction of the time that the FSSP is unable to count and size particles (its “dead time”). The activity fraction is not measured directly but is estimated from fast resets and total strobes along with measurements of the dead times associated with each (as determined in laboratory tests). The characteristic times are in the NetCDF header (for recent projects). .

FSTROB = strobes generated by particles in the depth-of-field,  
 per sample interval

FRESET = “fast resets” generated per sample interval

$t_1$  = slow reset time (for each strobe)

$t_2$  - fast reset time (for each fast reset)

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$$FACT = \{FSTROB\} t_1 + \{FRESET\} t_2$$

#### **PCAS Raw Activity (dimensionless); AACT, PACT**

The PCAS probe provides this measure of dead time, the time that the probe is unable to sample particles because the electronics are occupied with processing particles. The manufacturer suggests that the actual dead time ( $f_{PCAS}$ ) is given by the following formula, which is used in determining concentrations for the PCAS:

$$f_{PCAS} = 0.52 \frac{\{\text{PACT}\}}{F_{PCAS}}$$

where  $F_{PCAS} = 1024 s^{-1}$ . However, PACT (or AACT) is the variable archived in the data files.

**PMS-2D Cloud Probe Particle Concentration ( $L^{-1}$ ): CON2C1**

This concentration of all particles sensed by the PMS-2D Cloud Probe is based on the “shadow-or” count (SDWC1,SHDORC) from the probe. This counter is triggered each time a particle passes through the laser beam, so the rate at which these counts are produced can be used with the sample volume of the probe and the flight speed to determine this upper estimate of the particle concentration.

**PMS-2D Precip Probe Particle Concentration ( $L^{-1}$ ): CON2P1**

This measurement is based on SDWP1 or SHDORP and is analogous to CON2C1 but for the PMS-2D Precip Probe.

## 6.3 Hydrometeor Imaging Probes

– NEEDED: 2DC, 2DP, CPI, etc

## 7 AIR CHEMISTRY MEASUREMENTS

### **Raw Carbon Monoxide Concentration (ppb): CO**

CO is the uncorrected output of the TECO model 48 CO analyzer. This instrument measures the concentration of CO by gas filter correlation. The optics of the version operated by the RAF have been modified to increase the light through the absorption cell, and a zero trap has been added that periodically removes CO from the sample air stream to obtain an accurate zero. This permits correction for the significant temperature-dependent drift of the zero level of the measurement.

### **Carbon Monoxide Analyzer Status (V): CMODE,**

### **Carbon Monoxide Baseline Zero Signal (V): COZRO**

### **Raw Carbon Monoxide, Baseline Corrected (V): COCOR**

CMODE records if the CO analyzer is supplied with air from which CO has been removed and so is recording its zero level. When CMODE is less than 0.2 V, the instrument is in the normal operational mode, and when CMODE is greater than 8.0 V the instrument is in the “zero” mode. When measurements are processed, the zero-mode signals are represented by a cubic spline to obtain a reference baseline for the signal (COZRO), and this baseline is subtracted from the measured value (CO) to obtain COCOR. This variable still jumps to zero periodically and does not include the calibration that enters the following variable, COCAL.

### **Corrected Carbon Monoxide Concentration (ppmv): COCAL**

COCAL is the calibrated signal after correction for drift of the baseline and after application of the appropriate calibration coefficients to produce units of ppmv. The quality of the baseline fit can be judged by examining the offset at the zero points. If there are relatively small changes in the baseline, the zero offset will be only a few ppbv. If there have been rapid changes in the baseline, the zero offset can be up to 50 ppbv. The magnitude of the offset at the zero values gives a good measure of uncertainty in the data set. The detection limit is 10 ppbv, with an uncertainty of  $\pm 15\%$ . At 1 Hz, data will have considerable variability, so 10-s averaging is often useful when the measurements are used for analysis.

### **Raw TECO Ozone Output (ppb): TEO3**

TEO3 is the uncorrected output of the TECO 49 UV ozone analyzer. This commercial instrument has been modified to record the temperature and pressure inside the ozone absorption cell.

### **Internal TECO Ozone Sampling Pressure (mb): TEP, TEO3P**

### **Internal TECO Ozone Sampling Temperature ( $^{\circ}\text{C}$ ): TET**

TEP (or TEO3P) is the pressure inside the detection cell of the TECO 49 UV ozone analyzer, and TET is the cell temperature. These are used to convert the measurements from the instrument to units of ppbv.

### **Corrected TECO Ozone Concentration (ppbv): TEO3C**

TEO3C is the measurement from the TECO 49 UV ozone analyzer after correction for the pressure and temperature in the cell. The instrument provides output only each ten seconds, and measurements are collected in the 3 s preceding the update. The measurements may be artificially high or low when rapid changes in humidity are present, as may occur when

crossing the top of the boundary layer or when going through clouds. In operation on the ground prior to takeoff or immediately after landing, a high concentration of hydrocarbons can cause spuriously high measurements. The detection limit is 1 ppbv with an uncertainty of  $\pm 5\%$ .

**NO Raw Counts (counts per sample interval):** XNO

**NO<sub>y</sub> Raw Counts (counts per sample interval):** XNOY

**NO Calibration Flow (slpm):** XNOCF

**NO<sub>y</sub> Calibration Flow (slpm):** XNCLF

**NO, NO<sub>y</sub> Measurement Status (dimensionless):** XNST

**NO Zero Air Flow (slpm):** XNOZA

**NO<sub>y</sub> Zero Air Flow (slpm):** XNZAF

**NO Sample Flow (slpm):** XNOSF

**NO<sub>y</sub> Sample Flow (slpm):** XNSAF

**NO<sub>y</sub> Reaction Chamber Pressure (mb):** XNOYP

**Gold NO<sub>y</sub> Converter Temperature (°C):** XNMBT

XNO and XNOY are the raw data counts from the NO and NO<sub>y</sub> instruments, respectively, and XNCLF and XNOCF are the respective calibration flows for these instruments. XNST records the status for both instruments: In measurement mode, XNST is 0, while XNST is 5 when the instruments are in zero mode and 10 when the instruments are in calibration mode. the NO<sub>y</sub> and NO instruments. The instrument is in the measure mode for XNST of 0. For a XNST reading of 5 the instruments are in the zero mode. XNST value of 10 is the calibration mode. XNOZA and XNZAF are flow rates for zero air used to back flush inlets, typically at takeoff and landing, and for calibration using “zero” air. Even if the status, XNST, is 0, indicating the instrument is in the measurement mode, when XNOZA and XNZAF are approximately 1 slpm the instrument is measuring zero air and not ambient air. XNOSF and XNSAF are the sample flow rates through the NO and NO<sub>y</sub> instruments respectively. These values are typically about 1 slpm. XNMBT is the temperature of the gold NO<sub>y</sub> converter.

**Corrected NO Concentration (ppbv):** XNOCAL

**Corrected NO<sub>y</sub> Concentration (ppbv):** XNYCAL

XNOCAL and XNYCAL are the calibrated NO and NO<sub>y</sub> concentrations, respectively, with units of ppbv. The NO and NO<sub>y</sub> data are represented by a cubic spline for baseline subtraction, and then the calibration coefficients are applied and the measurements are converted to units of ppbv. The quality of the data can be assessed by examining the accuracy of the zero correction. This instrument adds water vapor to the sample stream to reduce the effect of ambient water on the final signal. The water vapor addition is not sufficient to saturate the sample stream, but enough to remove much of the interference. The detection limits of the NO,NO<sub>y</sub> instruments are 50 ppbv for a one-second averaging time. The uncertainty is  $\pm 5\%$ .

**Raw Chemiluminescent Ozone Signal (V):** O3FS

Raw output from the reverse chemiluminescence ozone instrument, which operates on the basis of reacting nitric oxide with ozone and detecting the resulting chemiluminescence.

**Chemiluminescent Ozone Sample Flow Rate (sccm):** O3FF

**Chemiluminescent Ozone Nitric Oxide Flow Rate (sccm):** O3FN

**Chemiluminescent Ozone Sample Pressure (mb):** O3FP

These variables characterize conditions within the chemiluminescence ozone sensor. The sample rate, in standard  $cm^3/s$ , is O3FF, while O3FN gives the NO flow rate in the same units and O3FP is the pressure in the ozone sample cell.

**Chemiluminescent Ozone Concentration (ppbv): O3FC**

This is the corrected ozone concentration, with units of ppbv. This instrument is calibrated both on the ground and in flight by comparison with the TECO 49 UV instrument. The final data are corrected for the influence of water vapor on the signal. The detection limit is 0.1 ppbv and the uncertainty is about 10% for a one-second sample.

## 8 AEROSOL PARTICLE MEASUREMENTS

RAF uses a modified TSI, Inc. Model 3760 condensation nucleus counter to measure the concentration of particulates in the atmosphere larger than about  $0.01\ \mu\text{m}$  diameter. Individual inlets have been designed for each research aircraft that provide approximately isokinetic flow at research airspeeds. The CN counter is often used as a stand-alone instrument, but it also can be placed downstream of various instruments, such as a counterflow virtual impactor or differential mobility analyzer. It is useful at altitudes up to about 11km. It operates by condensing n-butyl alcohol on the particles as they pass through a cooling/condenser tube where supersaturation of a few hundred percent is produced. The particles grow large enough to be seen by a laser-diode optical detector, and the pulses from that detector are counted to obtain an estimate of the total concentration of aerosol particles. The counter does not resolve particle concentration by size; the lower size limit of the TSI 3760 is about  $0.01\ \mu\text{m}$ , and all particles above that size enter the measurement of the total concentration.

If large concentrations are encountered, two or more particles may be present in the viewing volume at once and will produce only a single pulse from the photodetector. This “coincidence” error, which increases from about 0.6% at a total concentration of  $10^3/\text{cm}^3$  to about 6% at  $10^4\text{cm}^{-3}$ ; a correction for these effects of coincidence is applied, but for concentrations above about  $2 \times 10^4\text{cm}^{-3}$  effects of coincidence become large enough that the correction introduces significant uncertainty in the measurements.

The variables associated with these measurements of condensation-nucleus concentrations are discussed in the remainder of this section.

### **CN Counter Inlet Pressure (mbar): PCN**

PCN is the absolute pressure inside the inlet tube of the instrument, as measured by a Heise Model 623 pressure sensor. The measurement is used to correct the sample flow rates (FCN and XICN) that are used to obtain measurements of concentration.

### **CN Counter Inlet Temperature ( $^{\circ}\text{C}$ ): TEMP1, TEMP2, CNTEMP**

TEMP1, TEMP2 or CNTEMP is the output from a temperature sensor mounted on the outside of the sampling tube immediately ahead of the counter. The measurement, an approximation to the temperature of the air passing through the tube, is used to correct the sample flow rates (FCN and XICN).

### **Raw CN Counter Sample Flow Rate (slpm): FCN**

### **Corrected CN Counter Sample Flow Rate (vlpm): FCNC**

FCN is the raw sample flow rate in standard liters per minute (slpm) measured with a Sierra 830 Mass Flow meter. The flow meter measures the flow rate that would apply under “standard” conditions; i.e., pressure of 1013.25 and temperature of  $0^{\circ}\text{C}$ . FCNC is the sample flow rate in vlpm (volumetric liters per minute) corrected for pressure and temperature.

PCN = pressure at the inlet to the CN counter (mb)  
 TEMP1 = temperature at the inlet of the sample tube ( $^{\circ}\text{C}$ )  
 $P_{ref}$  = standard reference pressure, 1013.25 mb  
 $T_{ref}$  = standard reference temperature, 293.26 K

$$\text{FCNC} = \{\text{FCN}\} \frac{P_{ref}}{\{\text{PCN}\}} \frac{(\{\text{TEMP1}\} + T_0)}{T_{ref}}$$

**Raw CN Isokinetic Side Flow Rate (slpm): XICN**

**Corrected CN Isokinetic Side Flow Rate (vlpm): XICNC**

XICN is the raw isokinetic side flow rate in standard liters per minute (slpm) measured with a Sierra 830 Mass Flow meter, and XICNC is that flow corrected for pressure and temperature to be the true volumetric flow. For isokinetic sampling, the flow rate at the inlet entrance needs to equal the true airspeed, and for proper operation the flow rate through the CN counter should be at least 1.2 vlpm. A side flow of filtered air is added so both of these conditions can be met.

PCN = pressure at the inlet to the CN counter (mb)  
 TEMP1 = temperature at the inlet of the sample tube ( $^{\circ}\text{C}$ )  
 $P_r$  = standard reference pressure, 1013.25 mb  
 $T_r$  = 293.26 K

$$\text{XICNC} = \{\text{XICN}\} \frac{P_r}{\{\text{PCN}\}} \frac{(\{\text{TEMP1}\} + T_0)}{T_r}$$

**TSI CN Counter Output (counts per sample interval): CNTS**

CNTS is the raw output count from the TSI, Inc. 3760 condensation nucleus counter. The project-dependent sample rate may be chosen in the range from 1–50 Hz. In some unusual cases the counts are divided by a selected power of two to keep the counter from overflowing; see the project documentation.

**Condensation Nucleus (CN) Concentration ( $\text{cm}^{-3}$ ): CONCN**

CONCN is the corrected concentration of condensation nuclei, calculated with consideration of the sample rate and corrected for losses caused by coincidence:



CNTS = counts per second from the CN counter

$\Delta T$  = interval between recorded samples

$D$  = scale factor (normally 1)

FCNC = corrected sample flow rate ( $cm^3/s$ )

$T_{vv}$  = time each particle is in the view volume =  $4.167 \times 10^{-6}$  s

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$$A = \frac{\{CNTS\}}{\{FCNC\}\Delta T} D$$

$$CONCN = A e^{AT_{vv}\{FCNC\}} \quad (31)$$

See the introduction to this section for comments regarding the range of validity of the coincidence correction in Eq. (31).

## 9 RADIATION VARIABLES

### 9.1 Measurements of Irradiance and Radiometric Temperature

#### Radiometric (Surface or Sky/Cloud-Base) Temperature ( $^{\circ}\text{C}$ ): RSTx

Radiometric temperature is the equivalent black body temperature measured by one of two infrared radiometers. The x denotes either that the instrument is mounted on the bottom (B) or top (T) of the aircraft. Both of these instruments are calibrated using a black-body source manufactured by Eppley. The measurements may come from either of the following two instruments:

- a narrow bandwidth, narrow field-of-view ( $2^{\circ}$ ) Heimann Model KT-19.85 precision radiation thermometer. The wavelength range is 9.6 to 11.5  $\mu\text{m}$ .
- a narrow bandwidth, narrow field-of-view ( $2^{\circ}$ ) Barnes Engineering Model PRT-5 precision radiation thermometer. This instrument is now retired. The spectral bandwidth available was either 8 to 14  $\mu\text{m}$  or 9.5 to 11.5  $\mu\text{m}$ . Its cavity temperature was monitored and recorded as either TCAVB or TCAVT.

#### Radiometer Sensor Head Temperature ( $^{\circ}\text{C}$ ): TRSTB

This is the temperature of the sensing head of the Heimann radiometer, usually from RSTB, the primary down-looking instrument.

#### Raw Pyrgeometer Output ( $\text{W m}^{-2}$ ): IRx

A pyrgeometer manufactured by Eppley Laboratory, Inc. measures long-wave irradiance using a calibrated thermopile. It has a coated glass hemisphere that transmits radiation in a bandwidth between 3.5  $\mu\text{m}$  and 50  $\mu\text{m}$ . It is calibrated at RAF according to procedures specified by Albrecht and Cox (1977). The pyrgeometers are usually flown in pairs, one up-looking and one down-looking. The letter 'x' denotes either bottom (B) or top (T).

#### Corrected Infrared Irradiance ( $\text{W m}^{-2}$ ): IRxC

Because the pyrgeometer measures net radiation, IRx must be corrected for emission from the dome covering the sensor and for emission from the thermopile itself. IRxC is the corrected infrared irradiance, determined following procedures of Albrecht and Cox (1977). .

IRx = raw pyrgeometer output [ $\text{W m}^{-2}$ ]

$T_D$  = dome temperature [K]

$T_S$  = "sink" temperature (approx. the thermopile temperature) [K]

$\epsilon$  = emissivity of the thermopile (dimensionless) = 0.986

$\beta$  = empirical constant dependent on the dome type = 5.5

$\sigma$  = Stephan-Boltzmann constant =  $5.6704 \times 10^{-8} \text{ W m}^{-2} \text{ K}^{-4}$

$$\text{IRxC} = \text{IRx} - \beta \sigma (T_D^4 - T_S^4) + \epsilon \sigma T_S^4$$

**Shortwave Irradiance ( $\text{W/m}^2$ ): SWx**

An Eppley Laboratory, Inc., pyranometer measures short-wave irradiance. The dome normally used is UG295 glass, which gives wide coverage of the solar spectrum (from  $0.285 \mu\text{m}$  to  $2.8 \mu\text{m}$ ). Different bandwidths can be obtained by use of different glass domes, available from RAF upon request. (See Bulletin No. 25.) The pyranometers are usually flown in pairs, one up-looking and one down-looking. They are calibrated periodically at the NOAA Solar Radiation Facility in Boulder, Colorado. The letter 'x' denotes either bottom (B) or top (T).

**Corrected Incoming Shortwave Irradiance ( $\text{W/m}^2$ ): SWTC**

The down-welling shortwave irradiance measured by the difference between SWT and SWB) is corrected to take into account the sun angle and small variations in the aircraft attitude angles (pitch and roll). The correction is limited to  $\pm 6^\circ$  in either angle, so these measurements should be considered invalid beyond these limits. This is the derived output of incoming (down-welling) shortwave irradiance, taking into account both solar position (sun angle) and modest variations in aircraft attitude (at present, restricted to less than  $6^\circ$  in pitch and/or roll). (For more information, refer to Bulletin No. 25.)

**Ultraviolet Irradiance ( $\text{W/m}^2$ ): UVx**

A pair of UV radiometer/photometers measure either down-welling ( $x=T$ ) or up-welling ( $x=B$ ) irradiance in the ultraviolet, approximately from  $0.295 \mu\text{m}$  to  $0.385 \mu\text{m}$ . These units are periodically returned to the Eppley Laboratories for recalibration.

## 9.2 SOLAR ANGLES

The calculations described in this group are used primarily for deriving the Corrected Short Wave irradiance (SWTC) but can be used by themselves or in conjunction with other measurements that need them.

**Solar Declination Angle (radians): SOLDE**

This is a calculation of the astronomical measurement of solar declination angle, the angular distance of the sun north or south of the earth's equator. (Positive values are north.) To obtain this, the solar hour angle is calculated (taking leap years into account). The calculations were adapted by Ron Ruth from an algorithm developed by Lutz Bannehr.

time = day number (corrected for leap year) since 1 January 1980  
 theta = coarse solar time (radians)  
 gg = equation-of-time term for calculating declination (radians)  
 el = equation-of-time term for calculating declination (radians)  
 eps = equation-of-time term for calculating declination (radians)

---


$$\begin{aligned} gg &= -0.031271 - (4.53963e-7 \text{ time}) + \theta \\ el &= 4.900968 + (3.67474e-7 \text{ time}) \\ &\quad + \{[0.033434 - (2.3e-9 \text{ time})] \sin(gg)\} \\ &\quad + [0.000349 \sin(2 gg) + \theta] \\ sel &= \sin(el); \\ eps &= 0.409140 - (6.2149e-9 \text{ time}) \\ SOLDE &= \arcsin \{sel \sin(eps)\} \end{aligned}$$
**Solar Zenith Angle (radians): SOLZE**

This is the astronomical measurement of solar zenith angle, the angle from zenith to the sun, complementary to the sun's elevation angle:

lat = latitude (radians)  
 lha = local hour angle (radians)  
 SOLDE = solar declination angle (radians)

---


$$\begin{aligned} SOLZE &= \arcsin \{ \sin(lat) \sin(SOLDE) \\ &\quad + \cos(lat) \cos(SOLDE) \cos(lha) \} \end{aligned}$$
**Solar Azimuth Angle (radians): SOLAZ**

This is the astronomical measurement of solar azimuth angle, the angular distance between due south and the projection of the line of sight to the sun on the ground. A positive solar azimuth angle indicates a position east of south (i.e., morning).

lha = local hour angle (radians)  
 SOLDE = solar declination angle (radians)  
 SOLZE = solar zenith angle (radians)

---


$$SOLAZ = \arcsin \{ \cos(SOLDE) \sin(lha) / \cos(SOLZE) \}$$
**Solar Elevation Angle (radians): SOLEL**

This is the astronomical measurement of solar elevation angle, describing how high the sun appears in the sky. The angle is measured between an imaginary line between the observer and the sun and the horizontal plane on which the observer is standing. The altitude angle

is negative when the sun drops below the horizon.

SOLZE = solar zenith angle (radians)

---

$$\text{SOLEL} = \text{Pi}/2 - \text{SOLZE}$$

## **10 EXPERIMENTAL VARIABLES**

This bulletin does not document experimental variables, conventionally denoted by variable names starting with 'X'. Project documentation should be consulted for such variables. Many projects also include measurements from instruments provided by investigators outside NCAR/RAF. Identification of those variables, and processing algorithms, are contained in the project documentation and/or the NETCDF headers.

## 11 OBSOLETE VARIABLES

RAF retired the “GENPRO” processor, the software program previously used to produce data sets, in 1993, but data files produced by that processor are still retained and available for use. Also, there are some instruments that are now retired but provided measurements in some archived data files. Obsolete variable names that are associated only with GENPRO or a retired instrument are discussed below, for reference and to facilitate use of old data files.

### **Unaltered Tape Time (s): TPTIME**

This variable is derived by converting the HOUR, MINUTE and SECOND to elapsed seconds after midnight of the current day. If time increments to the next day, its value is not reset to zero, but 86400 seconds are added to produce ever-increasing values for the data set.

### **Processor Time (s): PTIME**

This is an internal time variable created by the GENPRO processor. It represents elapsed seconds after midnight. It differs from TPTIME in that, after it has been set at the beginning of the data set, it is incremented internally for each second of data processed. If duplicate or missing raw data records exist, it can differ from TPTIME. It is guaranteed to be a monotonically increasing and continuous series of values.

### **INS: Data System Time Lag (s): TMLAG**

TMLAG is the amount of time between the reference time of a Litton LTN-51 Inertial Navigation System (INS) and the data system clock, in seconds. TMLAG will always be greater than zero and less than 2.

### **LORAN-C Latitude (°): CLAT**

### **LORAN-C Longitude (°): CLON**

### **LORAN-C Circular Error of Probability (n mi): CCEP**

### **LORAN-C Ground Speed (m/s): CGS**

### **LORAN-C Time (s): CSEC**

### **LORAN-C Fractional Time (s): CFSEC**

Before the advent of GPS, NCAR/RAF operated a LORAN-C receiver that provided information on the position and groundspeed of the aircraft. The measurements of latitude and longitude from this system are CLAT and CLON, measured at 1 Hz and with positive values of longitude to the east and positive values of latitude to the north. and CCEP provides an estimate of the uncertainty in those measurements (in units of nautical miles). A status word, CSTAT, was used to record a value of 15 when the system was operational. The ground speed and reference times were also recorded in the above corresponding variables. The sum of CSEC and CFSEC represented the time of the measurement, which was not always the time in the data file when the measurements were recorded,

**INS Latitude (°): ALAT**

**INS Longitude (°): ALON**

**Raw INS Ground Speed X Component (m/s): XVI**

**Raw INS Ground Speed Y Component (m/s): YVI**

**Raw INS True Heading (°): THI**

**INS Wander Angle (°): ALPHA**

**INS Platform Heading (°): PHDG**

These variables from the Litton LTN-51 Inertial Navigation System (INS) are analogous to the modern variables discussed in section 3. The measurements of latitude and longitude were provided with 1-Hz frequency and had a resolution of 0.0014°, while the ground speed components were provided at 10 Hz and had resolution equal to 0.012 m/s. The X component of the ground speed was along the longitudinal axis of the aircraft *at the time of alignment*, and the Y axis was in the starboard direction at the time of alignment. PHDG recorded the orientation of the platform relative to true north, with resolution 0.0028°. THI was the true heading of the aircraft, produced at 5 Hz with resolution of 0.0014°. The “wander angle” is an INS-only variable that recorded the angle of the INS platform x-axis relative to its original orientation; it “wandered” in response to east-west motion of the aircraft on a spherical Earth.

**Raw Aircraft Vertical Velocity (m/s): VZI**

This is an integrated output from an up/down binary counter connected to the INS vertical accelerometer. Resolution is 0.012 m/s. Due to changes in local gravity and accumulated errors, this often develops a significant offset during flight.

**Aircraft True Heading (°): THF**

This measurement of aircraft heading was derived from the angle between the horizontal projection of the aircraft center and true north:  $THF = PHDG + ALPHA$ . Resolution is 0.0028°.

**Aircraft Ground Speed (m/s): GSF**

**Aircraft Ground Speed East Component (m/s): VEW**

**Aircraft Ground Speed North Component (m/s): VNS**

These variables have the same names as the modern variables for ground speed. (Cf. section 3.) GSF is the magnitude of the ground speed determined by the INS, as derived from XVI and YVI:

$$GSF = \sqrt{\{XVI\}^2 + \{YVI\}^2}$$

VEW and VNS are the east and north projections of this ground speed, derived using THF for the aircraft heading.

**Wind Speed (m/s): WSPD**

**Wind Direction (°): WDRCTN**

These variables are calculated from UI and VI, the east and north components of the wind determined as described in RAF Bulletin No. 23 and summarized in section 5:



$$WS = \sqrt{\{UI\}^2 + \{VI\}^2}$$

$$WD = \frac{180^\circ}{\pi} \text{atan2}(-\{UI\}, -\{VI\}) + 180^\circ$$

**Raw Attack Force (Fixed Vane) (g): AFIXx**

AFIXx is an amplified output from a strain-gage, fixed-vane sensor mounted in the horizontal plane of the aircraft at the end of a gust boom. The “force” on the vane (calibrated in “equivalent grams” at Jefferson County Airport gravity) varies as a function of the aircraft attack angle and dynamic pressure. Here x refers to left or right.

**Raw Sideslip Force(Fixed Vane) (g): BFIXx**

BFIXx is an amplified output from a strain-gage, fixed-vane sensor mounted in the vertical plane of the aircraft at the end of a gust boom. The “force” on the vane (calibrated in “equivalent grams” at Jefferson County Airport gravity) varies as a function of the aircraft sideslip angle and dynamic pressure. Here x refers to top or bottom.

**Attack Angle (Fixed Vane) (°): AKFXx**

AKFXx is the angle of attack, computed from AFIXx and QCx (either boom or gust dynamic pressure). An empirically derived function, HSSATK, is used to determine the attack angle based upon wind tunnel test data.

**Sideslip Angle (Fixed Vane) (°): SSFXx**

SSFXx is the sideslip angle, computed from BFIXx, and QCx (either boom or gust dynamic pressure). An empirically derived function, HSSATK, is used to determine the sideslip angle based upon wind tunnel test data.

**Dynamic Pressure (Boom) (mb): QCB, QCBC****Dynamic Pressure (Gust Probe) (mb): QCG, QCGC**

These variables, measured by a differential pressure gauge, record the difference between a pitot (total) pressure and a static pressure. The QCBC and QCGC values are corrected for local flow-field distortion. The boom and gust probe measurements referred to the same aircraft structure. The different designations used for those measurements specified the transducer used and its location. In the gust probe dynamic pressure measurement (QCG), a Rosemount Model 1332 differential pressure transducer was located closer to the sensor in the gust probe itself, whereas in the boom measurement (QCB), a Rosemount Model 1221 pressure transducer was typically located in the aircraft nose.

**Total Temperature, Reverse Flow (°C): TTRF**

TTRF is the recovery temperature from a calibrated NCAR reverse-flow temperature sensor, for which the housing was designed to separate water droplets and protect the element from wetting in cloud.

**Total Temperature (Fast Response) (°C): TTKP**

This is the output of recovery temperature from the NCAR fast-response temperature

probe, originally designed by Karl Danninger. (See discussion of total temperature in section 4.2.)

**Ambient Temperature (°C): ATRF**

The ambient temperature computed using the NCAR reverse-flow temperature sensor. (See discussion in Section 4.2 above.)

**Ambient Temperature (Fast Response) (°C): ATKP**

The ambient temperature computed using the fast-response temperature probe. (See discussion of ambient temperature in section 4.2.)

**Raw Cloud Technology (Johnson-Williams)**

**Liquid Water Content ( $g/m^3$ ): LWC**

This is the raw output of a Johnson-Williams liquid water content sensor converted to units of grams per cubic meter. The Johnson-Williams indicator measures the evaporative cooling caused by the latent heat of vaporization of droplets contacting the heated sensing element by sensing changes in its resistance as it cools. Through calibration this resistance is converted to a liquid water content. A “compensation” wire is also mounted in the J-W sensor, parallel to the droplet stream, to compensate for cooling effects of the airstream. Typically the instrument is set for a true airspeed of 200 knots. The instrument must be zeroed in “cloud-free air.” The Johnson-Williams liquid water content sensor is designed for the cloud droplet spectrum. There is some evidence to indicate that droplets larger than  $30\ \mu m$  are shed before completely vaporizing on the sensor element. This tends to underestimate the liquid water content.

**Corrected Cloud Technology (Johnson-Williams)**

**Liquid Water Content ( $g/M^3$ ): LWCC**

This is the corrected liquid water content obtained by using the aircraft’s true airspeed after removing the zero offset:  $LWCC = LWC U_a / U_{ref}$  where  $U_a$  is the true airspeed of the aircraft and  $U_{ref}$  is the true airspeed set on the dial of the instrument.  $U_{ref}$  was normally 200 kts = 102.88889 m/s.

**Water Vapor Pressure (mb): EDPC**

This is a derived intermediate variable used in the calculation of several derived thermodynamic variables. The vapor pressure over a plane water surface is obtained by the method of Paul R. Lowe (1977), a derived, sixth-order, Chebyshev polynomial fit to the Goff-Gratch Formulation (1946) as a function of temperature expressed in °C. The error is much less than 1% over the range -50°C to +50°C. EDPC was calculated using this method for most RAF research projects between 1993 and 1996. This variable did not have the enhancement factor applied that was discussed in Appendix C of Bulletin 9.

A.  $T < -50$  C:

$$\begin{aligned}\text{EDPC} &= 4.4685 + T(0.27347 + T\{6.83811 \times 10^{-3} \\ &+ T[8.7094 \times 10^{-5} + T(5.63513 \times 10^{-7} + T 1.47796 \times 10^{-9})]\})\end{aligned}$$

B.  $T \geq -50^\circ\text{C}$ :

$$\begin{aligned}\text{EDPC} &= 6.107799961 + T [0.4436518521 + T(0.01428945805 \\ &+ T\{2.650648471 \times 10^{-4} + T [3.031240396 \times 10^{-6} \\ &+ T(2.034080948 \times 10^{-8} + T 6.136820929 \times 10^{-11})]\})]\end{aligned}$$

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