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The EUMETSAT  
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# **Algorithm Theoretical Basis Document for the OSI SAF wind products**

**Ocean and Sea Ice SAF**

**Version 1.2  
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## KNMI, De Bilt, the Netherlands

*Reference:* SAF/OSI/CDOP2/KNMI/SCI/MA/197

## Contents

1.	Introduction.....	4
1.1.	Overview.....	4
1.2.	References .....	4
2.	Scatterometer instrument concepts .....	8
3.	Algorithms .....	10
3.1.	Wind definition .....	10
3.2.	Input screening .....	12
3.3.	NWP Ocean Calibration .....	13
3.4.	Spatial representation .....	13
3.5.	NWP collocation.....	13
3.6.	Wind retrieval.....	14
3.6.1.	Fan beam scatterometers.....	14
3.6.2.	Pencil-beam scatterometers.....	14
3.7.	Quality control.....	15
3.8.	Sea ice screening .....	16
3.9.	Ambiguity removal .....	16
3.10.	Product monitoring.....	16
4.	Wind processing .....	18
5.	Glossary .....	19

# 1. Introduction

## 1.1. Overview

The EUMETSAT Ocean and Sea Ice Satellite Application Facility (OSI SAF) produces a range of air-sea interface products, namely: wind, sea ice characteristics, Sea Surface Temperatures (SST) and radiative fluxes, Surface Solar Irradiance (SSI) and Downward Long wave Irradiance (DLI).

KNMI is involved in the OSI SAF as the centre where the level 1 to level 2 scatterometer wind processing is carried out. This document is the Algorithm Theoretical Basis Document to the wind products. More general information on the OSI SAF project is available on the OSI SAF web site: <http://www.osi-saf.org/>. Information about and status of the specific wind products can be found on <http://www.knmi.nl/scatterometer/>.

The scatterometer is an instrument that provides information on the wind field near the ocean surface, and scatterometry is the knowledge of extracting this information from the instrument's output. Space-based scatterometry has become of great benefit to meteorology and climate in the past years, see e.g. [Ref-1], [Ref-2].

KNMI has a long experience in scatterometer processing and is developing generic software for this purpose. Processing systems have been developed for the ERS, NSCAT, SeaWinds, ASCAT, Oceansat-2, RapidScat and HY-2A/HSCAT scatterometers. Scatterometer processing software is developed in the EUMETSAT Numerical Weather Prediction Satellite Application Facility (NWP SAF), whereas wind processing is performed operationally in the Ocean and Sea Ice SAF (OSI SAF). The algorithms developed for the various steps in the wind retrieval are shared between the processing software for the different instruments, but some details differ depending on instrument characteristics like antenna configuration and frequency band used. This document provides a general overview and also briefly describes the differences between the instruments.

Web resources that may be consulted and which complement this ATBD are:

- [KNMI scatterometer website](#);
- [KNMI publications website](#);
- [Training workshop](#) for scatterometer NWP data assimilation on the NWP SAF website;
- Training course on applications of satellite wind and wave products for marine forecasting, available in [video](#) or [document](#) forms;
- International Ocean Vector Winds Science Team meeting [presentations](#);

Following the introduction, section 2 of this document presents an overview of the various scatterometer instrument concepts, section 3 provides the processing algorithms and section 4 gives a brief overview of the wind processing of the different products in near-real time.

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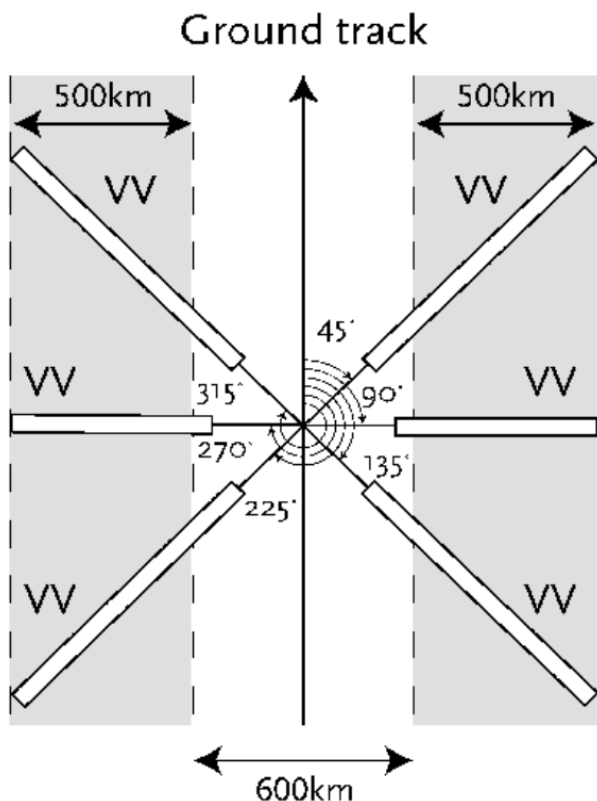
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References marked with a (\*) are available on <http://www.knmi.nl/scatterometer/publications/>.

## 2. Scatterometer instrument concepts

The scatterometer is a non-nadir looking real aperture radar instrument. Wind vector information over the oceans can be empirically derived from it. Over the last decades, scatterometers on-board satellites have provided very valuable sea surface wind field information. In addition to the meteorological and oceanographic use of scatterometer winds, the scatterometer data are of interest in applications such as sea ice detection and land surface soil moisture determination. In terms of antenna geometry, the scatterometer systems can be classified as side-looking and rotating scatterometers.

Side-looking scatterometers consist of a set of static fan-beam antennas pointing to one or both sides of the satellite flight track. Examples of such instruments are the NASA Scatterometer (NSCAT) on-board ADEOS-1, the scatterometers on the European Remote Sensing Satellites ERS-1 and ERS-2, and the Advanced SCATterometer (ASCAT) on-board Metop. An example of the illumination pattern of a side-looking scatterometer is shown in Figure 1. This pattern shows the coverage of ASCAT which has, contrary to ERS, two sets of antennas looking to either side of the satellite ground track. ERS only has one set of three antennas looking to the right side of the satellite track.



**Figure 1:** Earth surface coverage of the scans of the side-looking ASCAT scatterometer (source: [Ref-7]). Each location in the swaths is illuminated by the fore, the mid, and the aft beam as the satellite propagates towards the top of the page.

In contrast to side-looking scatterometers, the rotating scatterometers have a set of rotating antennas that sweep the Earth surface in a circular pattern as the satellite moves. The antennas can either be pencil (or spot) beams, as used for SeaWinds on-board QuikSCAT, OSCAT on-board Oceansat-2 and RapidScat on-board the International Space Station, or fan beams, as being built for the scatterometer on-board CFOSAT. See Figure 2 for the ground illumination pattern of SeaWinds or OSCAT. Due to the conical scanning, a swath location is generally viewed by each beam when looking forward (fore) and a second time when looking aft. As such, up to four measurement classes (called “view” here) emerge: horizontally polarised (HH) fore, HH aft, vertically polarised (VV) fore, and VV aft, in each Wind Vector Cell (WVC). The 1800-km-wide swath covers 90% of the ocean surface in 24

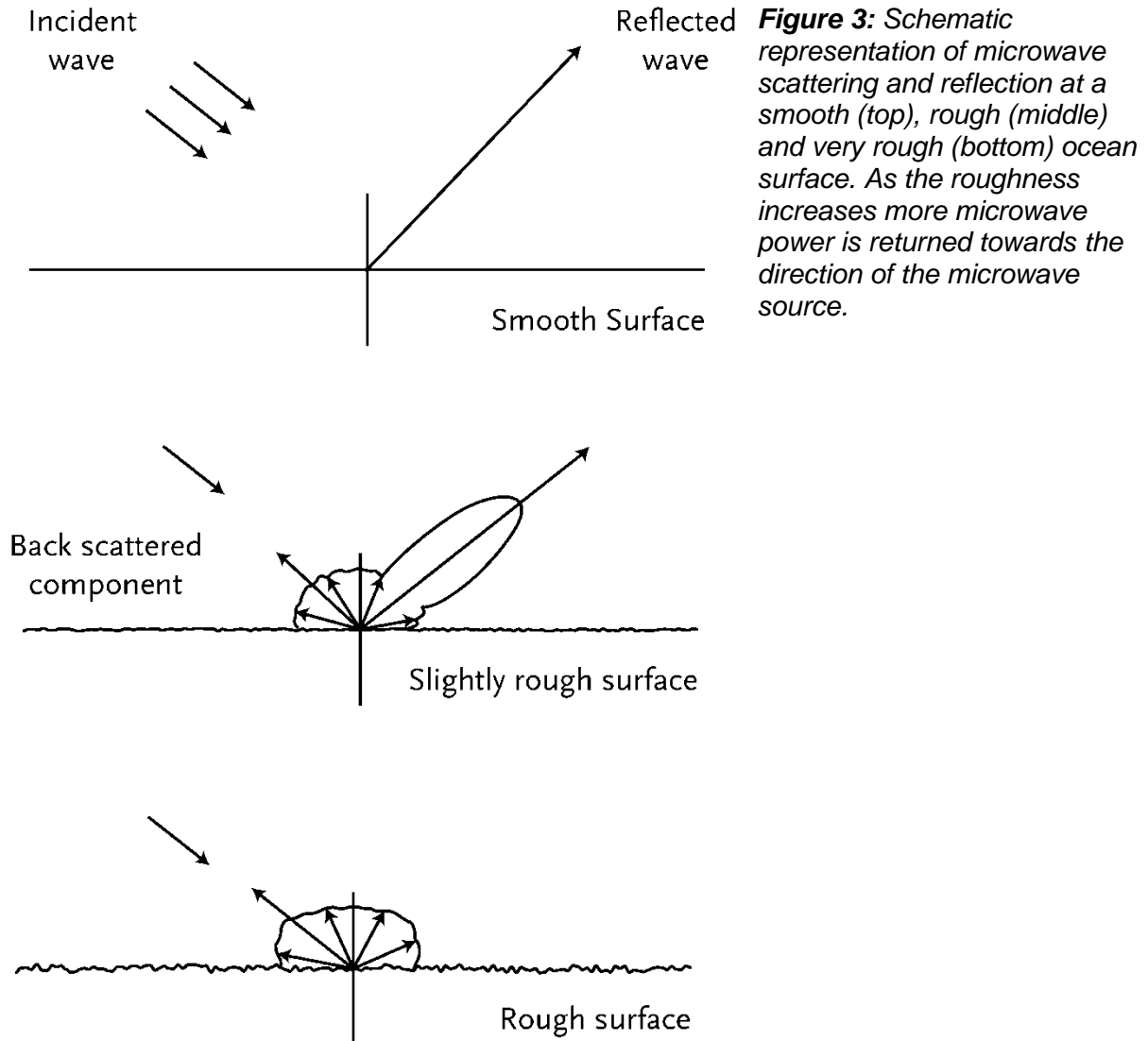




### 3. Algorithms

Scatterometry was developed heuristically. It was found experimentally that the sensitivity to wind speed and direction well describes the changes in backscatter over the ocean at moderate incidence angles due to changes in surface roughness. This is depicted in figure 3 [Ref-6]. In return, backscatter measurements can be used to determine the wind speed and wind direction in a WVC.

A schematic illustration of the processing is given in figure 4. After defining the wind output and motivating the Geophysical Model Function that is used, the algorithms developed at KNMI are described.



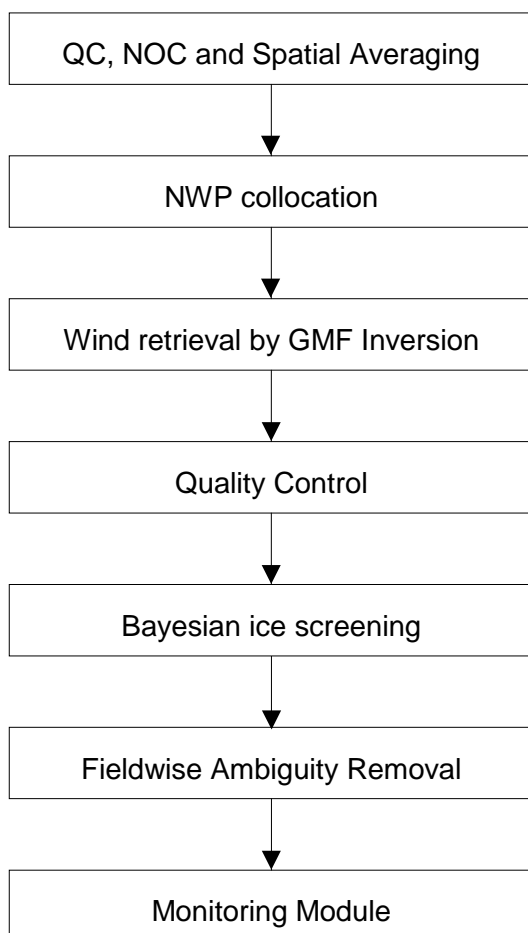
#### 3.1. Wind definition

A scatterometer measurement relates to the ocean surface roughness (see figure 3), while the scatterometer product is represented by the equivalent-neutral (EN) wind at 10 meter height over a WVC. The EN wind transforms the sea surface roughness measurements to 10 m height in a unique way and independent of atmospheric stratification [Ref-20]. Moreover, EN winds are straightforward to compute at most buoy locations and from NWP model output for validation and comparison. It is important to realize that in the approach

followed here the radar backscatter measurement  $\sigma^0$  is related to the EN wind at 10 meter height above the ocean surface, simply because such wind measurements are widely available for validation as 10 m is a World Meteorological Organization (WMO) reference height. This means that any effect that relates to the mean wind vector at 10 meter height is incorporated in the backscatter-to-wind relationship. As such, the appearance of surface slicks, and the amplitude of gravity or longer ocean waves, depend to some degree on the strength of the wind and may, to the same degree, be fitted by a Geophysical Model Function, GMF ([Ref-7], Chapter I). Stoffelen ([Ref-7], Chapter IV) discusses a unique method to determine the accuracy of scatterometer, buoy, and NWP model winds by triple collocation.

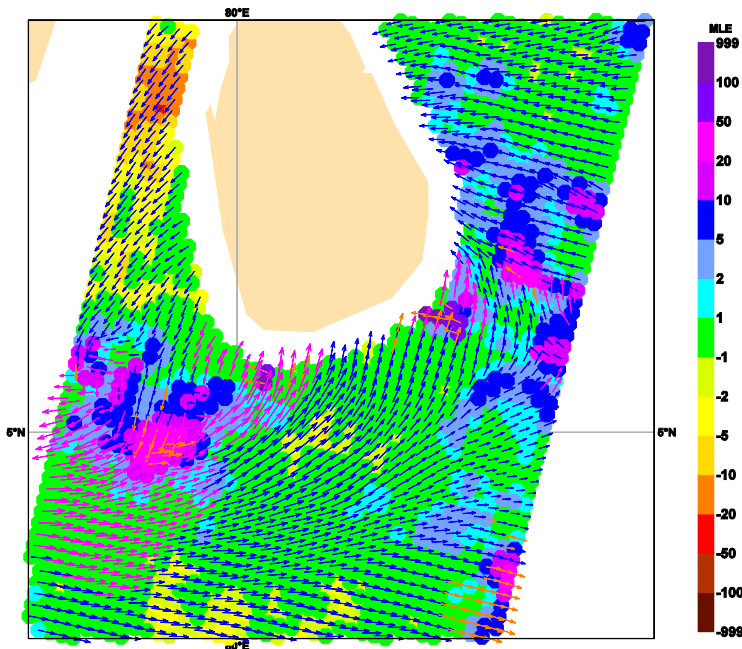
At low wind speeds the wind direction and speed may vary considerably within the WVC. Locally, below a speed of roughly 2 m/s calm areas are present where little or no backscatter occurs, perhaps further extended in the presence of natural slicks that increase the water surface tension [Ref-8]. However, given the variability of the wind within a footprint area of 25 km it is, even in the case of zero mean vector wind, very unlikely that there are no patches with roughness in the footprint. As the mean vector wind increases, the probability of a calm patch will quickly decrease, and the mean microwave backscatter will increase. Also, natural slicks quickly disappear as the wind speed increases, and as such the occurrence of these is correlated to the amplitude of the mean vector wind over the footprint, as modelled by the GMF. Low scatterometer wind speeds are thus providing useful information [Ref-9], [Ref-10].

**Figure 4:** Overview of wind retrieval algorithm



The wind variability varies on the globe. This implies for scatterometer measurements, being averaged over a large area, that the Probability Density Function (PDF) of contributing wind directions to a backscatter measurement varies over the globe as well. Wind direction

variability acts to reduce the wind direction modulation of the GMF. For example, if wind blows from all directions in a WVC, then wind direction cannot be determined at all. On the other hand, steady winds tend to have higher wind direction GMF modulation than more nominal wind regimes. So, the anisotropy (azimuth direction dependence) of ocean radar backscatter is a function of local wind variability in the WVC (Figure 5).



**Figure 5:** ASCAT wind (arrows) and wind variability (colours) at the ocean surface near Sri Lanka on 25 Nov 2011 3:45 UTC. The maximum winds just south of the island are 20 m/s; some of these wind arrows are coloured purple after flagging by 2DVAR, and some orange, after inversion Quality Control. The wind direction variability (MLE) is low to the northwest of the island (red colours; steady flow) and very high to the southwest and southeast (purple colours) due to severe convection that caused fatalities on this day.

At high wind speeds wave breaking will further intensify, causing air bubbles, foam and spray at the ocean surface, and a more and more complicated ocean topography. Although theoretically not obvious, it is empirically found that  $\sigma^0$  keeps increasing for increasing wind speed from 25 m/s to 40 m/s, and that a useful wind direction dependency remains [Ref-11], albeit gradually weakening. HH (used for Ku-band scatterometers only) and VH polarization (planned for the second generation ASCAT) measurements are more sensitive to extremely high winds than the nominal VV polarization [Ref-11].

### 3.2. Input screening

Backscatter input products contain flags to denote anomalous (instrument) conditions, which are obviously checked before wind retrieval. Examples of such flags are

- The ERS Missing Packet Counters and ERS ESA Quality Control flag
- The ASCAT Sigma0 Usability Flag (must be at least 'usable')
- The OSCAT flags for 'Sigma0 is poor', 'Kp is poor', 'Invalid footprint' and 'Footprint contains saturated slice'.
- For SeaWinds and RapidScat: all bits in the SeaWinds Sigma0 Quality Flag, except the 'Negative' flag.

Additional tests concern the ranges of the input data, i.e. at least for backscatter values; noise estimates ( $K_p$ ), azimuth and incidence angles, but also land occurrence and latitude and longitude position. Any data where the values are out of range are not used in the wind processing.

### **3.3. NWP Ocean Calibration**

Mean ocean backscatter is quite variable following transient large-scale weather patterns. However, these weather patterns are well analysed in NWP and NWP information may be used to correct for these large-scale variations. Stoffelen [Ref-25] introduced NWP Ocean Calibration (NOC) and this method evolved to a powerful procedure to detect instrument anomalies and provide intercalibration of scatterometer systems, i.e., ERS and ASCAT or QuikSCAT and OSCAT. NOC is being employed for ERS [Ref-26] and ASCAT [Ref-27] in order to provide winds of constant quality. For OSCAT it is also considered [Ref-28], but not yet implemented since some issues remain that are not fully understood. The NOC procedure aims to find a representative mean backscatter value for each WVC view, independent of the weather, over a period of a year. NOC may be used for monitoring purposes as well over periods as short as a day or the entire mission [Ref-29].

### **3.4. Spatial representation**

It is effective for radars to obtain measurements with a signal-to-noise ratio (SNR) close to unity. Since mean backscatter measurements over a WVC need to have a SNR of only a few percent to achieve sufficient wind quality, spatial averaging of many measurements is needed. Each measurement field of view (FOV) has typical dimensions of 10 to 20 km, often smaller in one dimension than in the other, and the FOVs centred in a particular WVC will extend out of the WVC on all sides, leading to some WVC overlap [Ref-14]. It also leads to complications in scatterometer wind processing near land and sea ice boundaries and the development of dedicated products, optimised in coastal regions [Ref-30].

The larger the WVC size chosen, the lower the noise in the averaged backscatter values, as more FOVs are integrated. Low noise and larger WVC sizes have advantages in NWP data assimilation, since NWP models do generally not resolve scales below 5-10 times their grid distance, see e.g. [Ref-31]. Lower resolution products are obtained by averaging available higher resolution backscatter products. On the other hand, in cases of extreme gradients (large signal), e.g., near polar lows or tropical hurricanes, shift meteorologists may appreciate high resolution winds, at the expense of some additional noise. The choice of spatial averaging approach allows addressing these preferences, after careful validation always ensuring that the resulting spatial representativeness of the data is adequate for the application intended.

In products optimised for coastal regions, for example, only FOVs over water are used to construct WVC backscatter values. This improves the wind coverage in coastal areas, but the WVC positions may be displaced away from the coast due to the exclusion of FOVs over land in the averaging. This leads to slight irregularities in the WVC spacing.

Note that the probability of occurrence of extremely high winds is substantially reduced by spatial averaging, since extreme winds are generally limited in spatial extent. Therefore, scatterometer winds and NWP winds, lacking variability on the smallest scales, are expected to be associated with a narrower wind speed PDF than local buoy winds averaged over 1 or 10 minutes [Ref-32].

### **3.5. NWP collocation**

NWP forecast wind data are necessary in the ambiguity removal step of the processing. Wind forecasts from the ECMWF global model are available twice a day (00 and 12 UTC analysis time) with forecast time steps of +3h, +6h, +9h and so on. The model wind data are cubically interpolated with respect to time and linearly interpolated with respect to location and put into the level 2 information part of each WVC.

It is important to note that scatterometer winds are being assimilated into the ECMWF model and therefore the wind field used for ambiguity removal (i.e., a forecast) is taken to be independent from the scatterometer observation. In near-real time processing the scatterometer measurement is received at approximately the same time at KNMI and

ECMWF, and the scatterometer winds are produced at KNMI within a few minutes typically. Hence the observation cannot yet have been assimilated into the ECMWF model fields at the moment of processing at KNMI.

For scatterometer wind reprocessing, ERA-Interim data are used [Ref-33]; here observations are assimilated in the model up to 3 hours after the analysis time. Therefore, in the processing of those observations, only forecast winds starting from 3 hours after analysis time are used. In this way independence between the scatterometer and the ECMWF model winds used to guide the wind direction ambiguity removal, is guaranteed.

### 3.6. Wind retrieval

In scatterometer wind retrieval a Geophysical Model Function (GMF) is inverted. The radar backscatter of the ocean, as derived from the GMF, depends, besides on the wind vector w.r.t. the radar beam pointing, on radar wavelength (C-band or Ku-band) and vertical (VV) or horizontal (HH) polarization. The inversion step combines the backscatter measurements in a WVC to compute the WVC-mean wind vector. Subtle, but very relevant, differences exist in the GMFs and inversion steps of C-band fan-beam and Ku-band pencil-beam scatterometers.

#### 3.6.1. Fan beam scatterometers

For the OSI SAF C-band scatterometer wind products (ERS and ASCAT), the CMOD5.n GMF for calculating equivalent neutral winds is used [Ref-18]. CMOD5.n is based on CMOD5 [Ref-19]. It is known from extensive validation work on ERS that a CMOD5 bias of 0.5 m/s against buoys persists for all wind speeds [Ref-20] and this is compensated. Moreover, another 0.2 m/s is added to convert from real winds to equivalent neutral winds. The CMOD5.n inverted winds are thus 0.7 m/s higher than CMOD5 winds.

The GMF has two unknowns, namely wind speed and wind direction. So, if more than two backscatter measurements with Gaussian noise are available then these two unknowns may be estimated using a quadratic estimator as the objective function for determining the wind vector [Ref-12]. Based on Bayes' probability theorem, the Maximum Likelihood Estimator, *MLE*, is redefined by ([Ref-7], Chapter II):

$$MLE = \frac{1}{SD^2} \sum_{i=1}^N (z_{o,i} - z_{m,i})^2$$

where  $z_{o,i}$  are the backscatter measurements,  $z_{m,i}$  are the simulated backscatter values corresponding to the measurements,  $i \in (1, N)$ , and  $SD$  is a measure of the measurement set noise standard deviation, related to both instrument noise and geophysical noise [Ref-13], [Ref-14];  $z = (\sigma^0)^{0.625}$  is a transformation that limits the wind direction sensitivity of the GMF to two harmonics. The wind direction sensitivity of the *MLE* function above is then approximately constant for the ERS and ASCAT fan-beam scatterometers and thus makes the inversion problem linear [Ref-13] and the *MLE* minima quadratic. Thus, the inversion of ERS and ASCAT measurement sets usually results in two well-defined local minima of the *MLE*, corresponding to two opposing wind vector solutions. The three independent measurements generally well sample the azimuth variation of the GMF and resolve the wind direction, albeit ambiguously.

#### 3.6.2. Pencil-beam scatterometers

For the OSI SAF Ku-band scatterometer wind products (SeaWinds and OSCAT) the NSCAT-2 GMF for calculating EN winds was used in the past [Ref-15]. Portabella ([Ref-3]; appendix C) compared the QSCAT-1 [Ref-17] and NSCAT-2 Ku-band GMFs for SeaWinds wind retrieval. He found that the QSCAT-1 results in more wind solutions during wind retrieval, i.e., it is more ambiguous. In other words, for QSCAT-1 we generally find more

minima when we inspect the *MLE* as a function of wind direction. Portabella verified that the additional minima are generally artificial and do not contribute to wind direction skill, i.e., act as a noise source. These additional local minima (noise) in the inversion do result potentially in local minima in ambiguity removal, even when using MSS, and thus in locally erroneous scatterometer wind field retrieval (see section 3.9).

A known problem of NSCAT-2 is that it overestimates wind speeds above 15 m/s, both when comparing to buoy winds and to NWP model winds. Hence, the NSCAT-2 GMF was changed for wind speeds above 15 m/s. The new GMF is called NSCAT-4. Below 15 m/s nothing was changed and the NSCAT-4 winds are identical to the NSCAT-2 retrieved winds. Above 15 m/s, a linear scaling of the wind speed was applied, starting with zero correction at 15 m/s, 2.5 m/s downward correction at 20 m/s, 5 m/s downward correction at 25 m/s and so on. This means that if a certain backscatter value results in a wind of 22.5 m/s in NSCAT-2, the same backscatter value will result in a wind of 20 m/s in NSCAT-4. The NSCAT-2 GMF lookup table was adapted in this way for all combinations of incidence and azimuth angles. This ensures that the fit in measurement space of the backscatter quadruplets to the GMF will not change. In [Ref-16] it was shown that NSCAT-4 provides a good fit of scatterometer wind speeds to both ECMWF and buoy winds. NSCAT-4 replaces NSCAT-2 for OSCAT and will be used for SeaWinds reprocessing and RapidScat processing as well.

In [Ref-13], Bayes' retrieval for the varying azimuth geometry of pencil-beam scatterometers is discussed and it is noted that such scatterometers are not sensitive to the wind vector for certain wind directions with a systematic variation by WVC. Therefore, the inversion procedure cannot be made linear and broad and skew *MLE* minima remain near these wind directions. Moreover, these wind directions "attract" local *MLE* minima and thus these local minima do not necessarily represent an optimal solution. The inherent broad and skew minima of pencil-beam scatterometers may be well represented in the wind vector solution space by the so-called Multiple Solution Scheme (MSS) that is used in the OSI SAF wind products [Ref-23]. In fact, for each wind direction the optimal speed is selected and its residual (*MLE*) is kept. The residuals are converted to probabilities, which are used in the ambiguity removal for all wind directions simultaneously, thus representing the full wind vector solution probability density function at each WVC.

### 3.7. Quality control

Since the scatterometer wind retrieval problem is over-determined, this opens up the possibility of quality control (QC) by checking the inversion residual. The inversion residual (*MLE*) is in theory inversely proportional to the log probability that a WVC is affected solely by a normal wind vector. Generally such probability is low, and the wind vector solution residual high, when rain affects the WVC, or when there is substantial wind or sea state variability within the cell [Ref-13], [Ref-14].

As such, Portabella and Stoffelen [Ref-21] found that the inversion residual is well capable of removing cases with extreme wind variability (at fronts or centres of lows), or with other geophysical variables affecting the radar backscatter, such as rain. QC is performed on the WVCs and rejection percentages vary between 3-7% for Ku-band and are below 1% for C-band systems. The KNMI QC procedure proves very effective, among others for screening rain in Ku-band scatterometers [Ref-36].

Steady flows show an increased harmonic dependence (anisotropy) of ocean radar backscatter and thus an elevated absolute *MLE* due to relatively poor correspondence with the GMF which has been derived for nominal wind conditions. Portabella et al. [Ref-37] found that the derived wind vectors are of good quality in such cases, but are degraded in cases of relatively isotropic ocean response. The latter are caused by (extreme) wind variability, rain splash [Ref-39] or perhaps confused sea states, which hamper the derivation of a representative wind vector. Therefore, a QC procedure has been implemented (for ERS and ASCAT) that only flags cases of increased isotropic response of the ocean backscatter [Ref-37].

### **3.8. Sea ice screening**

Following the developments on Bayesian wind retrieval, [Ref-4] and [Ref-5] provide scatterometer sea ice GMF and retrieval procedures. In fact, combining both wind and sea ice retrievals, the probability of sea ice may be computed, which shows very good sensitivity of scatterometer systems to sea ice cover, including over the melt season where passive microwave techniques appear less sensitive [Ref-4]. NWP model sea surface temperature (SST) data are used to support the Bayesian sea ice discrimination. WVCs with a sea surface temperature above 5 °C are assumed to be always open water. The ice screening procedure may sometimes assign rainy WVCs erroneous as ice; using the extra SST criterion, WVCs in warmer areas will never be labelled as ice. Due to its rather high threshold value, the NWP SST ice screening will only be active in regions far away from the poles.

### **3.9. Ambiguity removal**

Scatterometer winds have multiple ambiguities and there are up to four local minima after wind inversion in each WVC. These may be well-defined inversion minima, but also broad and skew minima (see section 3.3). The ambiguities are removed by applying constraints on the spatial characteristics of the output wind field, such as on rotation and divergence. The 2DVAR scheme closely resembles the 3D-var and 4D-var schemes applied in NWP data assimilation. Several ambiguity removal (AR) schemes were evaluated for ERS data [Ref-22]. In addition to the subjective comparison of AR schemes, a method for the objective comparison of AR performance among the different schemes was used. In [Ref-22] it is shown that this way of comparison is effective to evaluate the shortcomings of AR schemes, but also reveals a more general way forward to improve AR, which is followed up by adapting 2DVAR [Ref-34].

2DVAR uses a short-range NWP wind forecast valid at the time and location of the scatterometer measurements and subtracts it from the scatterometer wind solutions. The resulting ambiguous innovations and their probabilities are represented in the ambiguous scatterometer observation operator ([Ref-7], Chapter V). Vogelzang et al. [Ref-35] evaluate the general spatial covariance structure of these innovations and successfully apply the found NWP error covariance matrices in 2DVAR. Scatterometer observations appear generally spatially uncorrelated. The rotation and divergence structures in the specified NWP error covariances in 2DVAR have a clear effect on 2DVAR performance, while the quality of the prior forecast information appears less critical [Ref-34], [Ref-22].

To represent the variable inversion minima in the pencil-beam scatterometer processing, MSS is used. The probability density function of the wind solutions is represented by binning the full circle of possible wind directions into 144 equal sectors of 2.5° and for each wind direction an optimal wind speed with its corresponding probability is calculated in the wind retrieval step. Subsequently, the 144 solutions of each WVC are used in the AR to select the optimal solution.

### **3.10. Product monitoring**

For global coverage products, it is possible to generate a product monitoring flag, based on a multi-step check. If in one product the number of WVC Quality Control rejections, the mean residual, the wind speed bias with respect to the ECMWF NWP background or the wind vector RMS difference with respect to the background is above certain threshold values, typically 5 times the expected RMS values, then the monitoring event flag is raised since the product is suspicious. The threshold values are based on evaluation of the product statistics over a long period and maximise the probability of detection while minimising the false alarm rate [Ref-24].

In the case when the scatterometer product is not global but granular (like the ASCAT regional EARS products) and files containing only a few minutes of data are generated and disseminated in real-time, this mechanism raises problems if there are not enough data in



one pass for a statistically valid check. The multi-step monitoring check is sensitive to noise which is larger when mean values are calculated over fewer WVCs. If, accordingly, the thresholds are set high, many bad products will pass the check. On the other hand, if the threshold values are set too low, too many false alarms will be raised. This problem is solved by evaluating not only the data of the last processed pass, but by evaluating an amount of most recent data equivalent to the amount of half an orbit, although possibly originating from several different read-outs. In case of instrument degradation or other problems, the monitoring event flag will be raised with some delay, inherent to the discontinuous nature of a regional data stream.

## 4. Wind processing

KNMI has wind processing chains in place for several instruments, currently for ASCAT and RapidScat in near-real time. The near-real time processing of the scatterometer backscatter data to a wind product is done on KNMI's operational computing facilities. Reprocessing facilities exist or will be created for ERS, ASCAT, SeaWinds and OSCAT.

The wind processing software is developed within the Numerical Weather Prediction (NWP) SAF and consists of a generic part (called genscat) and a part that is specially designed to handle the data of a specific instrument. The genscat software consists of several modules devoted to e.g. reading and writing of BUFR and NetCDF data, collocation of scatterometer data with NWP fields, wind inversion and ambiguity removal. The instrument specific part of the software contains the main program control; it calls the different modules and routines in order to execute the processing steps as outlined in Figure 4.

Ancillary data from the ECMWF global model are present on a central location of the computing facilities. Scatterometer input swath data are normally received through the EUMETCast system. The granularity of the input data is different per product type: one input file containing from 3 minutes of data for ASCAT global products up to one orbit (90-100 minutes of data) for OSCAT and RapidScat. The granularity of the BUFR output data is the same as the granularity of the input data, for level 2 NetCDF the output data are always organised per orbit. Please see the corresponding Product User Manuals for more detailed information.

In the near-real time processing chains, a run control script is executed every few minutes and checks if any new data has arrived. If so, the new files are copied from the EUMETCast reception station location to a local directory, the NWP data valid at the time of the measurements is searched and the scatterometer data files are processed one by one. Each input file usually results in one output file containing wind data. Output files are sent to the KNMI FTP server, to the EUMETCast uplink station and to the GTS where appropriate.

In the reprocessing chains, long time series of wind products are created. Scatterometer and ECMWF input data are collected first from different archives and then the data processing and monitoring of the whole data set is controlled by a script.

## 5. Glossary

2DVAR	Two-dimensional Variational Ambiguity Removal
AR	Ambiguity Removal
ASCAT	Advanced Scatterometer
EN	Equivalent Neutral
ERS	European Remote-Sensing Satellite
EARS	EUMETSAT Advanced Retransmission Service
EUMETCast	EUMETSAT's Digital Video Broadcast Data Distribution System
EUMETSAT	European Organisation for the Exploitation of Meteorological Satellites
GMF	Geophysical Model Function
HH	Horizontal polarisation of sending and receiving radar antennas
HSCAT	Scatterometer on-board the Chinese HY-2A satellite
JPL	Jet Propulsion Laboratory (NASA)
KNMI	Royal Netherlands Meteorological Institute
MLE	Maximum Likelihood Estimator
MSS	Multiple Solution Scheme
NASA	National Aeronautics and Space Administration (USA)
NOAA	National Oceanic and Atmospheric Administration (USA)
NSCAT	NASA Scatterometer
NWP	Numerical Weather Prediction
OSCAT	Scatterometer on-board the Indian Oceansat-2 satellite
OSI SAF	Ocean and Sea Ice SAF
PDF	Probability Density Function
QC	Quality Control
QuikSCAT	USA dedicated scatterometer mission
RapidScat	SeaWinds-like scatterometer on-board the International Space Station
SAF	Satellite Application Facility
SeaWinds	Scatterometer on-board QuikSCAT platform (USA)
SST	Sea Surface Temperature
$u$	West-to-east wind component
$v$	South-to-north wind component
VV	Vertical polarisation of sending and receiving radar antennas
WMO	World Meteorological Organization
WVC	Wind Vector Cell