THE CZCS GEOLOCATION ALGORITHMS

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The Coastal Zone Color Scanner (CZCS) on board the Nimbus 7 satellite was designed to measure surface radiance upwelled from the ocean in 6 spectral bands. The CZCS spectrometer obtains its information from a rotating mirror and is timed to collect data when the mirror views the earth surface between ca. 40° to the left and right of the subsatellite track. Each scan is divided into 1968 picture elements, pixels, of 0.04 degrees scan each. In order to avoid direct reflected sun glint, the rotating mirror shaft can be tilted so that scans cross the subsatellite track up to 20° forward or aft of the point directly beneath the satellite. The CZCS is the first satellite borne instrument to have this tilted scan capability and therefore poses some new problems in locating the earth surface position of viewed pixels. This report restates results of analyses performed by several members of the Nimbus Experiment Team for the CZCS, using a consistent coordinate system and terminology.

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THE CZCS GEOLOCATION ALGORITHMS

The location on earth of a pixel viewed at a certain tilt and scan angle is a complex problem in CZCS viewing geometry and spherical trigonometry. Presented here is the derivation of the Visibility Laboratory algorithm for CZCS pixel location. It was originally developed by Wayne Wilson and Raymond Smith of the Visibility Laboratory, in collaboration with Jim Mueller of the Naval Post Graduate School, Monterey and Howard Gordon of the University of Miami.

SATELLITE GEOMETRY

Fig. 1 defines the coordinate system used relative to the satellite. Note: angles are symbolized by greek letters, vectors are symbolized by lower case letters superscripted with a bar (\( \bar{a} \)), and rotation operators, (matrices) are symbolized with capital letters.

DEFINITIONS

- **x axis**: The x axis is along the direction of flight of the satellite, positive towards the radiometer sensor.
- **z axis**: The z axis connects the center of the scan mirror and the center of the earth, positive towards the earth and orthogonal to x axis at the point of intersection.
- **y axis**: The y axis is orthogonal to the x and z axes.
- \( \bar{a} \): \( \bar{a} \) is the vector through the shaft of the scan mirror (the mirror rotates about this vector). Vector \( \bar{a} \) rotates about the y axis in the x-z plane defining the tilt angle \( \tau \).
- \( \bar{n} \): \( \bar{n} \) is a unit vector orthogonal to the surface of the scan mirror.
- \( \bar{d} \): \( \bar{d} \) is a unit vector along the x axis (oriented toward the sensor).
- \( \bar{v} \): \( \bar{v} \) is a unit vector from the direction of the pixel to the scan mirror. 
  
  *Note that vectors \( \bar{d}, \bar{n}, \) and \( \bar{v} \) lie in the same plane.*
- \( \theta_m \): \( \theta_m \) is the angle between \( \bar{d} \) and \( \bar{n} \).
- \( \tau \): \( \tau \) is the tilt angle of the scan mirror shaft. (One half the “tilt” given in the subcommutated data.)
- \( \eta \): \( \eta \) (not shown) is the mirror shaft rotation angle.
The tilt and scan angle are known parameters. From these we would like to calculate the nadir angle \( \theta \) from the z axis to vector \( \vec{v} \), and the azimuth angle \( \phi \) from the x axis to the projection of \( \vec{v} \) on the x-y plane (Fig. 2).

For convenience in the derivations to follow it is desirable to rotate the coordinate system above to a "natural" coordinate system such that \( z_n = x \), \( x_n = -z \), and \( y_n = y \) (Fig. 3). In this system the angles describing \( \vec{v} \) (\( \theta_n \) and \( \phi_n \)) can be more easily calculated from \( \tau \) and \( \eta \). After \( \vec{v} \) is described in terms of \( \theta_n \) and \( \phi_n \) the coordinates will be rotated to the "satellite" system and \( \theta \) and \( \phi \) derived.

Recall that vector \( \vec{n} \) is the normal to the scan mirror and therefore is dependant only on tilt and scan for its orientation. The initial position of vector \( \vec{n} \) at zero tilt and zero scan can be defined as lying in the \( x_n-z_n \) plane at an angle 45\(^\circ\) clockwise rotation from the \( z_n \) axis, (Fig. 4).
Since \( \vec{n} \) is a unit vector, its \( x_n, y_n, z_n \) coordinates may be calculated:

\[
\vec{n}_0 = \begin{bmatrix} x_n \\ y_n \\ z_n \end{bmatrix} = \begin{bmatrix} \cos \theta_m \\ 0 \\ \sin \theta_m \end{bmatrix} = \begin{bmatrix} -1 / \sqrt{2} \\ 0 \\ 1 / \sqrt{2} \end{bmatrix} = \begin{bmatrix} -a \\ 0 \\ a \end{bmatrix} .
\]

The CZCS mirror tilts about the \( y_n \) axis, (assumed to be through the surface of the mirror). The tilt angle \( \tau \) is defined positive when \( \vec{n} \) rotates in a counter clockwise direction. An Eulerian rotational operator \( T \) can be defined such that it acts on \( \vec{n} \) to cause a counter clockwise rotation about \( y_n \).

\[
T = \begin{bmatrix} \cos \tau & 0 & \sin \tau \\ 0 & 1 & 0 \\ -\sin \tau & 0 & \cos \tau \end{bmatrix} .
\]

The mirror scans about the mirror shaft; at zero tilt this shaft lies along the \( z_n \) axis. An Eulerian rotational operator \( S \) can be described to rotate \( \vec{n} \) around the \( z_n \) axis. When facing the negative \( z_n \) axis direction, this rotation is positive in a clockwise direction.

\[
S = \begin{bmatrix} \cos \eta & \sin \eta & 0 \\ -\sin \eta & \cos \eta & 0 \\ 0 & 0 & 1 \end{bmatrix} .
\]

We would like to combine the operators into a single operator. Normally one considers the CZCS mirror to scan about a tilted mirror shaft, however if we operate \( T \) on \( \vec{n} \) the mirror shaft (fixed in relation to \( \vec{n} \)) also rotates out of alignment with \( z_n \) and the use of \( S \) to scan about \( z_n \) becomes invalid. It is mathematically valid to scan \( \vec{n} \) about \( z_n \) first then tilt it about \( y_n \) second. Vector \( \vec{n} \) will have the same final coordinates and the simpler Eulerian operators can be used.

\[
TS = T \ (S) = \begin{bmatrix} \cos \tau \cos \eta & \cos \tau \sin \eta & \sin \tau \\ -\sin \eta & \cos \eta & 0 \\ -\sin \tau \cos \eta & -\sin \tau \sin \eta & \cos \tau \end{bmatrix} .
\]

Therefore for any \( \tau \) and \( \eta \),

\[
\vec{n}' = \begin{bmatrix} x_n' \\ y_n' \\ z_n' \end{bmatrix} = TS \begin{bmatrix} -a \\ 0 \\ a \end{bmatrix} = \begin{bmatrix} a(\sin \tau - \cos \tau \cos \eta) \\ a \sin \eta \\ a(\cos \tau + \sin \tau \cos \eta) \end{bmatrix} .
\]

We now have the coordinates for the mirror normal vector \( \vec{n} \) after scan and tilt and can proceed to derive the coordinates of vector \( \vec{v} \) from the direction of the pixel. Recall that vector \( \vec{d} \) is a unit vector lying along the \( z_n \) axis in the direction of the CZCS sensor.

\[
\vec{d} = \begin{bmatrix} 0 \\ 0 \\ 1 \end{bmatrix} .
\]

Vector \( \vec{d} \) is separated from vector \( \vec{n} \) by the angle \( \theta_m \). Because the angle of incidence to a mirror is equal to the angle of reflection, vector \( \vec{v} \) is also separated from \( \vec{n} \) by angle \( \theta_m \) and lies in the same plane as vectors \( \vec{d} \) and \( \vec{n} \).
Since vector \( \vec{v} \) is directed into the mirror and vector \( \vec{n} \) is directed away from the mirror, if vector \( \vec{v} \) is subtracted from vector \( \vec{n} \) the resulting vector will lie along \( \vec{n} \) with a length of \( 2 \cos \theta_m \), (Fig. 5).

\[
\vec{n} - \vec{v} = 2 \cos \theta_m \\
\vec{v} = \vec{n} - 2 \cos \theta_m \\
\vec{v} = \begin{bmatrix}
0 - 2 \cos \theta_m \cdot a \cdot (\sin \tau - \cos \tau \cos \eta) \\
0 - 2 \cos \theta_m \cdot a \cdot \sin \eta \\
1 - 2 \cos \theta_m \cdot a \cdot (\cos \tau + \sin \tau \cos \eta)
\end{bmatrix}
\]

With the coordinates of \( \vec{v} \), angle \( \phi_n \) can now be calculated,

\[
\tan \phi_n = \frac{y_n}{x_n} = \frac{\sin \eta}{\sin \tau - \cos \tau \cos \eta}
\]

Note that computational machines return arctangent functions in the range of ±90°. Therefore for normal scan angles 180° must be added to the returned value of \( \phi_n \), (Fig. 6). Therefore:

\[
\phi_n = 180° + \arctan \left( \frac{\sin \eta}{\sin \tau - \cos \tau \cos \eta} \right)
\]

Since \( |\vec{n}| = |\vec{n}| = 1 \),

\[
\vec{n} \cdot \vec{n} = |\vec{n}| |\vec{n}| \cos \theta_m = \cos \theta_m = a(\cos \tau + \sin \tau \cos \eta)
\]

\[
\theta_n = 2 \theta_m
\]

Fig. 5
\[ \theta_n = 2 \arccos \left( a \left( \cos \tau + \sin \tau \cos \eta \right) \right) \]

Vector \( \vec{v} \) is now described in the "normal" coordinate system in terms of the angles \( \theta_n \) and \( \phi_n \). To rotate back to the "satellite" coordinate system recall that:

\[
\begin{align*}
\text{"satellite"} & & \text{"normal"} \\
x &= \sin \theta \cos \phi & z_n &= \cos \theta_n \\
y &= \sin \theta \sin \phi & y_n &= \sin \theta_n \sin \phi_n \\
z &= \cos \theta & -x_n &= -\sin \theta \cos \phi_n
\end{align*}
\]

Therefore:

\[ \theta = \arccos(-\sin \theta_n \cos \phi_n) \]

and

\[ \phi = \arctan \left( \frac{y}{x} \right) = \arctan \left( \tan \theta_n \sin \phi_n \right) . \]

Due to the quadrant ambiguity of the arctangent function, for negative tilts, 180° may need to be added to \( \phi \) to correct \( \phi \).

**PITCH - ROLL - YAW**

The "satellite" coordinate system as defined above is fixed relative to the space craft. However, the satellite may be rotated due to pitch, roll, and/or yaw relative to an "earth" coordinate system. The origin of the "earth" system is the same as for the "satellite" system, the center of the satellite. The x direction is the instantaneous tangent to the flight path, the z direction is towards the center of the earth, and y is orthogonal to x and z. The "satellite" system will oscillate about the "earth" system by small angles generally less than a degree. Fig. 7 shows the directions of the pitch, roll, and yaw rotations on the "earth" system, these rotations define the orientation of the "satellite" system in Fig. 2.
At this point we have vector \( \vec{v} \) defined by angles \( \phi \) and \( \theta \) relative to the "satellite" coordinate system. The \( x, y, \) and \( z \) coordinates of \( \vec{v} \) may be calculated as in Eq. (1) above:

\[
\begin{align*}
x &= \sin \theta \cos \phi \\
y &= \sin \theta \sin \phi \\
z &= \cos \theta 
\end{align*}
\]

We now need to create a set of operators that will rotate the "satellite" \( x, y, z \) coordinates to a set of "earth" \( x', y', z' \) coordinates for \( \vec{v} \). The order of correction is significant. The \( xyz \) coordinates must first be pitched about the \( y \) axis, then rolled about the new \( x \) axis and finally yawed about the again new \( z \) axis. First the pitch operator:

\[
P = \begin{pmatrix}
\cos p & 0 & \sin p \\
0 & 1 & 0 \\
-sin p & 0 & \cos p
\end{pmatrix},
\]

where \( p \) equals the pitch angle. Next the roll operator:

\[
R = \begin{pmatrix}
1 & 0 & 0 \\
0 & \cos r & -\sin r \\
0 & \sin r & \cos r
\end{pmatrix}.
\]

Finally the yaw operator:

\[
Y = \begin{pmatrix}
\cos y & -\sin y & 0 \\
\sin y & \cos y & 0 \\
0 & 0 & 1
\end{pmatrix}.
\]

These may be combined by first multiplying \( R \) on \( P \) and then multiplying \( Y \) on \( RP \) yielding \( YRP \):

\[
YRP = \begin{pmatrix}
\cos y \cos p + \sin y \sin p \cos r & -\sin y \cos p + \cos y \sin p \cos r & \cos r \sin p \\
\sin y \cos r & \cos y \cos r & -\sin r \\
-\cos y \sin p + \sin y \sin p \cos r & -\sin y \sin p + \cos y \sin p \cos r & \cos r \cos p
\end{pmatrix}.
\]
Since we are dealing with small angles, considerable computation time can be saved by assuming the cosine of \( r, p, \) or \( y = 1 \), \((\cos 1^\circ = 0.9998)\). If working in the radians mode one can assume that the sine of \( r, p, \) or \( y \) equals \( r, p, \) or \( y \). Therefore, YRP becomes:

\[
YRP = \begin{bmatrix}
1 + yr p & -y + rp & p \\
-yr + p & 1 & -r \\
\end{bmatrix}
\]

If working in the degrees mode, first precompute \( \sin r, \) \( \sin p, \) and \( \sin y \).

Now we may multiply YRP on a set of "satellite" coordinates and calculate a set of "earth" coordinates for \( \vec{v} \).

For clarity let the satellite \( x, y, z \) coordinates be expressed as \( u, v, w \) to distinguish them from the angles \( r, p, \) and \( y \). Then:

\[
x' = (1 + yrp)u + (-y + rp)v + pw \\
y' = yu + v + rw \\
z' = (-p + yr)u + (-yp + r)v + w
\]

Notice that if roll, pitch, and yaw are zero, \( x' = u, y' = v, \) and \( z' = w \) as we would expect.

Finally, we can calculate \( \theta' \) and \( \phi' \) for the "earth" system:

\[
\theta' = \arccos (z') \\
\phi' = \arctan (y'/x')
\]

Due to the quadrant ambiguity of the arctangent function, for negative tilts, 180° may need to be added to \( \phi' \) to correct \( \phi' \).

**EARTH LOCATION**

If the latitude and longitude of a geographical position, and the distance and true bearing to a second geographical position are known, the latitude and longitude of the second geographical position can be calculated. Distance and true bearing from the satellite ground point to the pixel can be derived from \( \theta \) and \( \phi \), or \( \theta' \) and \( \phi' \) if correcting for roll, pitch, and yaw.

Given the orbital altitude of the satellite, \( h \), for example 952km, and the nadir angle \( \theta \), the surface distance, \( \delta \), in degrees great circle arc is:

\[
\delta = \arcsin (R \sin \theta) - \theta
\]

where

\[
R = (r + h)/r = 1.1494,
\]

and

\[
r = \text{earth mean radius} = 6371.2 \text{km}
\]

The inclination of the CZCS orbital trackline is a function of latitude, and is 9.28° (west of north) at the equator. For any latitude, the inclination, \( \alpha \), is:

\[
\alpha = \arcsin (\sin 9.28/\cos \text{lat})
\]
True bearing, $\beta$, then is $\phi - \alpha$, if $\beta$ is negative, $\beta = 360 + \beta$.

Fig. 8 represents a general spherical triangle.

**Points:**
- **G.P.**: G.P. is the ground point, subsatellite point, of the satellite.
- **$P_n$**: $P_n$ is the north pole.
- **$P_i$**: $P_i$ is the pixel.

**Angles:**
- $\beta$: $\beta$ is the true bearing from the satellite G.P. to the pixel.
- $\Delta\text{lon}$: $\Delta\text{lon}$ is the difference in longitudes between points G.P. and $P_i$.
- $\delta$: $\delta$ is the great circle distance between G.P. and $P_n$.
- $\text{Colat}_0$: $\text{Colat}_0$ is the co-latitude of the G.P. ($\text{Colat} = 90^\circ - \text{lat}$)
- $\text{Colat}_1$: $\text{Colat}_1$ is the co-latitude of the pixel.

If the latitude and longitude of the G.P. are known then the latitude and longitude of the pixel may be calculated directly. From the cosine rule:

$$\text{lat}_1 = \arcsin \left( \sin \text{lat}_0 \cos \delta + \cos \text{lat}_0 \sin \delta \cos \beta \right) . \tag{2}$$

A lat or lon subscripted with a 0 ($\text{lat}_0$) refers to the G.P. and those subscripted with a 1 ($\text{lat}_1$) refer to the pixel. Notice that the sine of the colatitude equals the cosine of the latitude, etc. From the sine rule

$$\Delta\text{lon} = \arcsin \left( \sin \beta \sin \delta / \cos \text{lat}_1 \right) . \tag{3}$$

Then,

$$\text{lon}_1 = \text{lon}_0 - \Delta\text{lon} .$$

These calculations work for all latitudes north (+) or south (-) to $\pm 80.72^\circ$ and all longitudes, (+ west, - east), for the north bound satellite track.
If the latitude and longitude of the pixel are known, then the calculation of the latitude of the G.P. is a complex quadratic equation since the true bearing, $\beta$, is a function of the unknown $\text{lat}_0$. From above:

$$\beta = \phi - \arcsin(\sin 9.28 / \cos \text{lat}_0).$$  \hspace{1cm} (4)

Let

$$I = \sin 9.28 / \cos \text{lat}_0.$$

Then

$$\beta = \phi - \arcsin I,$$

and we may substitute this in Eq. (2) above.

$$\text{lat}_1 = \arcsin (\sin \text{lat}_0 \cos \delta + \cos \text{lat}_0 \sin \delta \cos(\phi - \arcsin I)) .$$

The term containing $I$ may be rewritten:

$$\cos(\phi - \arcsin I) = \cos \phi \cos \arcsin I + \sin \phi \sin \arcsin I.$$  \hspace{1cm} (5)

Note that

$$\cos \arcsin I = \sqrt{1 - I^2}.$$

Therefore Eq. (5) equals:

$$= \cos \phi \sqrt{1 - I^2} + I \sin \phi$$

$$= \cos \phi \sqrt{1 - \sin^2 9.28 / \cos^2 \text{lat}_0} + \sin \phi \sin 9.28 / \cos \text{lat}_0$$

$$= \frac{\cos \phi}{\cos \text{lat}_0} \sqrt{\cos^2 \text{lat}_0 - \sin^2 9.28} + \frac{\sin \phi \sin 9.28}{\cos \text{lat}_0}.$$

Substituting this last back into Eq. (2) the $\text{lat}_0$ terms cancel yielding:

$$\sin \text{lat}_1 = \sin \text{lat}_0 \cos \delta + \sin \delta (\cos \phi \sqrt{\cos^2 \text{lat}_0 - \sin^2 9.28} + \sin \phi \sin 9.28).$$

This can be rearranged yielding:

$$\sin \text{lat}_0 \cos \delta + \sin \delta \cos \phi \sqrt{1 - \sin^2 \text{lat}_0} - \sin^2 9.28 = \sin \text{lat}_1 - \sin \delta \sin \phi \sin 9.28.$$  \hspace{1cm} (6)
Let
\[ x = \sin \text{lat}_0 \]
\[ a = \sin \text{lat}_1 - \sin \delta \sin \phi \sin 9.28 \]
\[ b = \cos \delta \]
\[ c = \sin \delta \cos \phi \]
\[ d = 1 - \sin^2 9.28 = \cos^2 9.28 \]

Equation (6) becomes:
\[ bx + c \sqrt{d - x^2} = a \]

Rearranging and removing the radical yields:
\[ x^2(b^2 + c^2) - x(2ab) + (a^2 - c^2 d) = 0 \]

Thus:
\[ x = \frac{ab \pm \sqrt{a^2 b^2 - (b^2 + c^2)(a^2 - c^2 d)}}{b^2 + c^2} \]

The value under the radical is chosen to be positive if tilt, \( \tau \), is negative and negative if tilt is positive. Then:
\[ \text{lat}_0 = \arcsin x \]

Note: It is simplest to precompute the values of \( a, b, c, \) and \( d \) before attempting to calculate \( x \).

Beta is now calculated as in Eq. (4), and \( \Delta \text{lon} \) is calculated as in Eq. (3). \( \text{lon}_0 \) then is:
\[ \text{lon}_0 = \text{lon}_1 + \Delta \text{lon} \]

**TABLE OF USEFUL INFORMATION**

Mean satellite orbital period (Nov-Dec 1980) = 104.07 minutes
Mean orbital velocity (great circle arc) = 5.765 x 10^{-2} degrees/second
Mean satellite orbital altitude (Nov-Dec 1980) = 952 kilometers
Satellite scan rate = 123.75 milliseconds/scan line
Trackline inclination angle = 9.28 degrees west of north
Mean earth radius = 6371.2 kilometers
Earth rotational velocity = 4.1667 x 10^{-3} degrees/second
**PROGRAM LISTINGS**

The following are listings of two sets of programs using the CZCS geolocation algorithms. First is a HPL program for the H.P. 9825 calculator. This program is primarily a set of subroutines which may be used for special stand alone applications. The calling routines, accessed by special function keys, provide basic calculations and may be easily modified for next loops to provide for example, trackline latitudes and longitudes.

Next, is a set of Fortran programs used in the Visibility Laboratory's CZCS atmospheric correction algorithm. These subroutines, "CZSUB1" - "CZSUB5" and "CZSUBA", provide all the basic algorithm calculations. Also included is "CZNVA", a utility program similar to the HPL program, which calls the various CZ Subroutines. All the Fortran programs are written to compile on a Prime 550 Computer. "CZNVA" is written in Fortran 77. The CZ Subroutines have been compiled using Fortran 77 but were written using Fortran 66 protocol.

0: "CZNVA":
1: "Stand alone CZCS tracking program":
2: "09 January 1981, VisLab, Nolten":
3: "dim L[6],m[2],CS[32]
4: gret "CZKEY"
5: 6=F;ent "Enter output device.",F;gsb "Notes"
6: gto "START"
7:
8: "----":for K=1 tc 35;wtb F," ";next K;wtb F,"--------",13,10;ret
9:
10: "ap":
11: "returns angles in degrees.minutes decimal minutes":
12: prnd(pl,-6)+pi;ret int(pi)+.6frc(pi)
13: "df":
14: "returns angles in decimal degrees":
15: ret int(pi)+frc(pi)/.6
16:
17: "dist":
18: "pi = nadir angle; returns p2 = distance":
19: asn((952+6371)/6371)sin(pl)*p2;p2-p1+p2
20: ret p2
21:
22: "pix":
23: "pl=tilt, p2=pixel #, returns: p3=azimutn, p4=nadir ang, p5=shaft ang":
24: -39.04+.04p2+p5
25: 2acs((cos(p1)+sin(p1)cos(p5))/2)+p6
26: 180+atn(sin(p5)/(sin(p1)-cos(pi)cos(p5)))+7
27: "theta":acs(-sin(pi)cos(p7))p4
28: if p6=90 or p6=270;sgn(p5)+2*180-90sgn(p5)+p3;jmp 2
29: "phi":atan(sin(p6)sin(p7)/cos(p6))p4;if p1<0;180+p3+p3
30: if not (w or X or Y);ret
31: "Roll-Piten-Yaw":
32: "x,y,z":sin(p4)cos(p3)+p8;sin(p4)sin(p3)+p9;cos(pi)+cos(p4)+p10
33: "sin (R.F.Y)":sin(w)+p11;sin(x)+p12;sin(y)+p13
34: "x'":(1+p11p12p13)p8+(-p13+p11p12)p9+p12p10+p14
35: "y'":p13p8+p12p10+p15
37: "theta":acs(pl6)p4
38: if p14;atan(p15/p14)+p20;if T<0;180+p20+p20
39: if not p14;sgn(p15)90+p20;if T<0;180+p20+p20
40: "phi":p20+p3
41: ret
42:
43: "pixdir":
44: "entry: pl=track line azimutn, p2=G.P. lat; return: p3=true bearing":
45: pl-asn(cos(8u.72)/cos(p2))+p3;if p3<0;360+p3+p3
46: ret p3
47:
48: "pixlat":
49: "entry: pl=G.P. lat, p2=stc dist, p3=true bearing; return: p4=pix lat":
50:  \(90-\text{pl}\cdot\text{p5}; \text{acs} (\cos(\text{p5}) \cos(\text{p2}) + \sin(\text{p5}) \sin(\text{p2}) \cos(\text{p3})) \cdot \text{p4} + 90-\text{p4} \cdot \text{p4}\)  
51:  \(\text{ret} \, \text{p4}\)  
52:  
53:  "\text{pixlon}":  
54:  "\text{entry: pl}=\text{Pix. lat}, \, \text{p2}=\text{G.P. lon}, \, \text{p3}=\text{sfc dist}, \, \text{p4}=\text{true bearing}":  
55:  "\text{return: p5}=\text{pixel longitude}":  
56:  \(\text{p2}-\text{asn} (\sin(\text{p4}) \sin(\text{p3}) / \sin(90-\text{pl})) \cdot \text{p5}\)  
57:  \(\text{ret} \, \text{p5}\)  
58:  
59:  "\text{equa}":  
60:  "\text{entry}: \text{pl}=\text{GP lat}, \, \text{p2}=\text{GP lon}; \text{return: p3}=\text{sec since}, \, \text{p4}=\text{deg since}":  
61:  "\text{p5}=\text{scan line since, p6}=\text{longitude of equator}":  
62:  \(\text{asn} (\sin(\text{pl}) / \sin(80.72)) \cdot \text{p4} / 5.765 \cdot 2 - \text{p3}\)  
63:  \(\text{p3} / 1.2375 - \text{p5} / \text{p2} - \text{asn} (\tan(\text{pl}) / \tan(80.72)) - 4.1667 \cdot 3 \cdot \text{p3} + \text{p6}; \text{ret} \, \text{p6}\)  
64:  
65:  "\text{scanli}":  
66:  "\text{entry}: \text{pl}=\text{seconds, p2}=\text{degrees}; \text{return: p3}=\text{scan lines}":  
67:  \(\text{if p2} \neq 0; \text{p2} / 5.765 \cdot 2 - \text{p1}\)  
68:  \(\text{pl} / 1.2375 + \text{p3}; \text{ret} \, \text{p3}\)  
69:  
70:  "\text{second}":  
71:  "\text{entry}: \text{pl}=\text{scan lines, return: p2}=\text{seconds, p3}=\text{degrees}":  
72:  \(\cdot 1.2375 \cdot \text{pl} + \text{p2} / 5.765 \cdot 2 - \text{p3}; \text{ret} \, \text{p2}\)  
73:  
74:  "\text{latlon}":  
75:  "\text{entry}: \text{pl}=\text{new sec since equa}, \, \text{p2}=\text{lon of equa}":  
76:  "\text{return: p3}=\text{new lat}, \, \text{p4}=\text{new lon}":  
77:  \(5.765 \cdot 2 + \text{p1} \cdot \text{p5}; \text{asn} (\sin(80.72) \sin(\text{p5})) + \text{p6}\)  
78:  \(\text{p2} + \text{asn} (\tan(\text{p6}) / \tan(80.72)) + 4.1667 \cdot 3 \cdot \text{p1} + \text{p4}; \text{p6} + \text{p3}; \text{ret}\)  
79:  
80:  "\text{GP}":  
81:  "\text{p1}=\text{Azimuth, p2}=\text{Distance, p3}=\text{Lat-l}; \text{return} \, \text{p4}=\text{Lat-0}":  
82:  \(\sin(\text{p3}) - \sin(\text{p2}) \sin(\text{pl}) \sin(9.28) + \text{r1}\)  
83:  \(\cos(\text{p2}) \cdot \text{r2}\)  
84:  \(\sin(\text{p2}) \cdot \cos(\text{pl}) \cdot \text{r3}\)  
85:  \(\cos(9.28) + 2 \cdot \text{r4}\)  
86:  \(\text{rl} \cdot \text{r2} + \text{r3} \cdot 2 + \text{r6}\)  
87:  \(\text{r5} \cdot 2 - \text{r6} \cdot (\text{rl} \cdot 2 - \text{r3} \cdot 2 \cdot \text{r4}) + \text{r7}\)  
88:  \(\text{if r7} > 0; \text{r7} \times \text{r7}\)  
89:  \(\text{if not} \, \text{sgn(T)} \cdot \text{r8}; \text{r1} \times \text{r8}\)  
90:  \(\text{asn} ((\text{r5} - \text{sgn(r8)} \cdot \text{r7}) / \text{r6}) + \text{p4}; \text{ret}\)  
91:  
92:  "\text{Iter}": \text{fxd} \, 0\)  
93:  \(\text{U}=\text{I} = 1.9699 + \text{V}\)  
94:  "\text{L1}):(U+V) / 2 + \text{P}; \text{c11 'pix'}('I/2, P, A, N, R)\)  
95:  \(\text{c11 'GP'}(A, \text{'dist'}(N, D), L[3], L[1])\)  
96:  \(\text{c11 'pixdir'}(A, L[1], B); L[4] + \text{asn} (\sin(B) \sin(D) / \cos(L[3])) + L[2]\)  
97:  \(\text{c11 'equa'}(L[1], L[2], S, O, M, K)\)  
98:  \(\text{I} + 1; \text{I} > 3, 999 + K\)  
99:  \(\text{if abs(K-L+R0)} < 0.00028 \text{ or } R=999; \text{gto } +4\)
100: if r0<0;P*U
101: if r0>0;P*V
102: gto "L1"
103: ret
104:
105: "START":
106: fmt c35," = ",fl5.4
107: beep;dsp "Key Special Function to Continue";stp
108:
109: "5":
110: "DegMin-DecDeg and ScanLine-Time conversions":
111: prt "Conversion Codes";fmt cl0," = ",c4
112: wrt 16,"seconds","S","scan lines","L","dec deg","DD","deg min","DM"
113: wrt 16,"QUIT","Q";spc 2
114: ent "Enter value and Identity code",CS
115: if pos(cap(C$),"Q");cll ' ';gto "START"
116: val(C$)=C
117: fmt l,10x,f7.2," SECONDS =",f6.0," SCAN LINES"
118: fmt 2,10x,f7.0," SCAN LINES =",f7.2," SECONDS"
119: fmt 3,10x,fl0.4," DEGREES MINUTES =",f10.4," DECIMAL DEGREES"
120: fmt 4,10x,fl0.4," DECIMAL DEGREES =",f10.4," DEGREES MINUTES";fxd 1
121: if pos(cap(C$),"S");wrt F+.1,C,'scanli'(C)
122: if pos(cap(C$),"L");wrt F+.2,C,'second'(C)
123: if pos(cap(C$),"M");wrt F+.3,C,'dd'(C)
124: if pos(cap(C$),"DD");wrt F+.4,C,'dm'(C)
125: gto -11
126:
127: "6":
128: "Enter Equa crossing Lon & Time, Sta. Lat-Lon, get sta pix vals & time":
129: ent "Enter Equatorial crossing Long.",L
130: ent "Time of crossing (HH.MMm)",Z
131: ent "Enter Station Latitiude",L[3],"Station Longitude",L[4],"Tilt",T
132: gsb "Iter"
133: wtb F,10,10
134: wrt F,"STATION LATITUDE","dm'(L[3]),"STATION LONGITUDE","dm'(L[4])
135: wrt F,"EQUATORIAL LONGITUDE","dm'(L),"TIME AT EQUATOR",Z
136: wrt F,"TILT",T
137: cll '-----';if R=999>wrt F,"STATION NOT SEEN THIS PASS, R",999;gto +4
138: wrt F,"TIME OF STATION PASSAGE","dm'('dd'(Z)+'dd'(S/6000))
139: wrt F,"STATION PIXEL NUMBER",prnd(P,0)
141: gto "START"
142:
143: "7":
144: "Enter Pixel Lat-Lon, Pixel #, get G.P. Lat-Lon, & Equa data":
146: cll 'pix'(r/2,P,A,N,R);cll 'dist'(N,D)
147: cll 'Gr'(A,D,L[3],L[1])
148: cll 'pixcir'(A,L[1],d);L[4]+asn(sin(B)sin(D)/cos(L[3]))-L[2]
149: cll 'equa'(L[1],L[2],S,O,M,L)
150: wtb F,10,10
151: wrt F,"PIXEL LATITUDE"),'dm'(L[3]),"PIXEL LONGITUDE",'dm'(L[4])
152: wrt F,"PIXEL #",P,"TILT",T
153: cll '----';wrt F,"G.P. LATITUDE",'dm'(L[1])
156: gto "START"
157:
158:
159:
160: "8":
161: "Enter Pixel Lat-Lon, X-Y corrd's, second pix X-Y corrd's,":
162: "Get second pixel Lat-Lon":
163: ent "Enter 1st Pixel lat.",L[3],"1st Pixel lon.",L[4],"1st Pixel #",P
164: ent "1st Pixel Scan line ",M[1],"Tilt",T
166: cll 'pix'(T/2,P,A,N,R);cll 'GP'(A,'dist'(N,D),L[3],L[1])
167: cll 'pixdir'(A,L[1],B);L[4]+asn(sin(B)sin(D)/cos(L[3]))*L[2]
168: cll 'equa'(L[1],L[2],S,0,M,L)
169: cll 'latlon'(S+sec(L[1])-L[2],L[1],L[2])
170: cll 'pix'(T/2,Q,A,N,R)
171: cll 'pixlat'(L[1],'dist'(N,D),'pixdir'(A,L[1],B),L[5])
172: cll 'pixlon'(L[5],L[2],D,B,L[6])
173: wtb F,10,10;wrt F,"FIRST PIXEL LONG",'dm'(L[4]),"FIRST PIXEL ",P
174: wrt F,"FIRST PIXEL SCANLINE ",M[1],"SECOND PIXEL ",Q
175: wtb F,"SECOND PIXEL SCAN LINE ",M[2],"TILT",T;gsb "----"
176: wtb F,"SECOND PIXEL LAT",'dm'(L[5]),"SECOND PIXEL LONG",'dm'(L[6])
177: gto "START"
178:
179:
180: "9":
181: "Enter Reference Pixel Lat-Lon, X-Y corrd's, station pix Lat-Long,":
182: "Get station pixel X-Y values":
183: ent "Enter Ref Pixel lat.",L[3],"Ref Pixel lon.",L[4],"Ref Pixel ",Q
184: ent "Ret Pixel Scan line ",M[1],"Enter Tilt",T
185: ent "Enter Station Latitude",L[3],"Station Longitude",L[4]
186: cll 'pix'(T/2,W,A,N,R);cll 'GP'(A,'dist'(N,D),L[5],L[1])
187: cll 'pixdir'(A,L[1],B);L[6]+asn(sin(B)sin(D)/cos(L[5]))*L[2]
188: cll 'equa'(L[1],L[2],S,0,M,L);M+M[2];gsb "Iter"
189: M[1]+(M[2]-M)*N;prnd(M,0)*M;prnd(P,0)*P
190: wtb F,10,10;wrt F,"REFERENCE PIXEL LATITUDE",'dm'(L[5])
191: wtb F,"REFERENCE PIXEL LONGITUDE",'dm'(L[6]),"REF PIXEL X VALUE",Q
192: wtb F,"REF PIXEL Y VALUE",M[1],"STATION LATITUDE",'dm'(L[3])
193: wtb F,"STATION LONGITUDE",'dm'(L[4]),"TILT",T;gsb "----"
195: gto "START"
196:
197:
198: "10":
199: "Enter G.P. Lat-Lon, Tilt, Pixel#; ret Pixel Lat-Lon":

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CZNAV

201: cll 'pix'((T/2,P,A,N);cll 'dist'(N,D)
202: cll 'pixdir'(A,L[1],B);cll 'pixlat'(L[1],D,B,L(3])
203: cll 'pixlon'(L[3],L[2],D,B,L(4])
204: wtb F,10,10
206: wtb F,"PIXEL #",P;cll '----'
207: wtb F,"DISTANCE TO PIXEL",D,"BEARING TO PIXEL",B
208: wtb F,"PIXEL LATITUDE","dm'(L[3]),"PIXEL LONGITUDE","dm'(L[4])
210: gto "START"
211:
212: "ll":
213: "Change Roll, Pitch, and/or Yaw":
214: ent "Enter Roll",w/'Pitch",X,"Yaw",Y
215: fmt 2/,25x,"NEW ROLL, PITCH, YAW:";wrt F
216: fmt c35," = ",f7.2;wrt F,"ROLL",W/'PITCH",X,"YAW",Y
217: gsb "-
218: gto "START"
219:
220: "Notes":
221: if F=701;fmt 3/;wrt 701
222: if F=6;wrt 6,102,125
223: fmt 7x,C
224: wtb F,6,"THE CZNAV PROGRAM CAN BE USED TO CALCULATE A VARIETY OF"
225: wtb F,"THE ROUTINES ARE ACCESSED BY USE OF"
226: wtb F,"IN DECIMAL DEGREES, OUTPUT IS IN DEGREES MINUTES."
227: wtb F,"FOR DEGREES-MINUTES ENTRY, FUNCTION KEY F0 WILL CONVERT THE"
228: wtb F,"ANGLE AND ENTER IT; USE KEY F0 INSTEAD OF THE CONTINUE KEY."
229: wtb F,"TILT IS INITIALIZED TO 20; ROLL, PITCH, YAW TO 0. TILT IS"
230: wtb F,"ASKED EACH TIME, USE F11 FOR R.P.Y. VARIABLES ARE GLOBAL."
231: wtb F,10,10
232: fmt "KEY",30x,"DESCRIPTION",/;wrt F
233: fmt 0,"F",f2.0," : ",c;fmt 1,7x,c;fxd 1
235: wtb F,6,"FROM EQUATORIAL CROSSING LONG, TIME, AND STATION LAT-LONG,"
236: wtb F,"CALCULATE TIME OF STATION PASSAGE AND PIXEL #."
237: wtb F,7,"FROM PIXEL LAT-LONG AND PIXEL #, CALCULATE G.P. LAT-LONG."
238: wtb F,8,"FROM 1ST PIXEL LAT-LONG, X-Y VALUES, AND 2ND PIXEL X-Y VALUES,"
239: wtb F,"CALCULATE 2ND PIXEL LAT-LONG."";
241: wtb F,"CALCULATE STATION PIXEL X-Y VALUES."
242: wtb F,10,"FROM G.P. LAT-LONG AND PIXEL #, CALCULATE PIXEL LAT-LONG."
243: wtb F,11,"ENTER NEW ROLL, PITCH, AND YAW VALUES."
244: wtb F,5,"DEG MIN - DEC DEG AND TIME - SCAN LINE CONVERSIONS."
245: wtb F,0,"DEGREES MINUTES ENTRY."
246: if F=701;wrt 701,12
247: ret
248:
249: "Variables":
250: "A = satellite azimuth to pixel":
251: "B = true bearing from G.P. to pixel":
252: "C = ":
253: "D = distance to pixel in degrees great circle arc":
254: "E = ":
255: "F = output device number":
256: "G = ":
257: "H = ":
258: "I = general counter":
259: "J = ":
260: "K = equatorial longitude used in 'Iter'":
261: "L = equatorial longitude of satellite crossing":
262: "M = scan lines from equator to G.P.":
263: "N = satellite nadir angle from G.P. to pixel":
264: "O = degrees great circle arc from equa. to G.P.":
265: "P = pixel number (primary or reference pixel)":
266: "Q = pixel number (secondary pixel)":
267: "R = satellite mirror shaft angle":
268: "S = seconds since equatorial crossing":
269: "T = satellite tilt angle (2 tau)":
270: "U = used in 'Iter'":
271: "V = used in 'Iter'":
272: "W = satellite roll angle":
273: "X = satellite pitch angle":
274: "Y = satellite yaw angle":
275: "Z = Time of equatorial crossing":
276: "L[*] = latitude-longitude array (odd=lat, even=lon)":

CZSUB1 - CZCS Navigation Subr #1

Given a CZCS G.P. latitude, longitude and travel time in seconds, this routine calculates a new G.P. latitude and longitude.

CALL CZSUB1 (XINCLP, PERIOD, XLATO, XLONGO, T, XLAT, XLONG, IERR)

CZSUB2 - CZCS Navigation Subr #2

Given the CZCS G.P. latitude, longitude, tilt, and scan angle, this subroutine will return the pixel latitude and longitude.

CALL CZSUB2 (XINCLP, ALTCOR, XLATO, XLONGO, TILT, XNU, XLAT, * XLONG, PITCH, ROLL, YAW, IERR)

CZSUB3 - CZCS Navigation Subr #3

This subroutine returns the Latitude and Longitude of the Ground Point of the Satellite. The input variables are the Latitude and Longitude, Tilt and Scan Angle of a Pixel, and the Roll, Pitch, and Yaw, Satellite altitude factor, and equatorial trackline inclination angle of the Satellite. See CZSUB Variable index for explanation of variable names.

CALL CZSUB3 (XINCLP, ALTCOR, XLAT, XLONGO, TILT, XNU, XLATO, * XLONGO, PITCH, ROLL, YAW, IERR)

CZSUB4 - CZCS Navigation Subr #4

Given a satellite G.P. latitude and longitude, this subroutine calculates the longitude or equatorial crossing, and the satellite travel time from the equator to the G.P.

CALL CZSUB4 (XINCLP, PERIOD, XLATO, XLONGO, XLONGP, T, IERR)
CZSUB5 - CZCS Navigation Subr #5

Given a pixel latitude and longitude and an equatorial crossing longitude, this subroutine iterates to find a satellite G.P. latitude and longitude which (1) contains the pixel in its scan and (2) crossed the equator at the given longitude. Also returned are the scan angle (XNU) and transit time (T). If the iteration fails, meaning no ground point meets the criteria, a value of -9999 is returned for XNU.

CALL CZSUB5(XINCLP,ALTCOR,PERIOD,XLONGP,XLAT,XLONG,TILT,
*XLATO,XLONGO,T,XNU,PITCH,ROLL,YAW,IERR)

CZSUBA - CZCS Navigation subr A

This is an internal subroutine called by several of the other CZCS navigation subroutines. Given the tilt, scan angle, roll, pitch, and yaw, this routine calculates the trackline relative bearing to the pixel, the effective scan angle, and the earth surface distance (in radians) from the satellite G.P. to the pixel.

SUBROUTINE CZSUBA(ALTCOR,TILT,XNU,RPSI,RTHS,RTH,PITCH,ROLL,YAW
* ,IERR)

CZSUB - VARIABLES

These are the variables named in the call lists in the various CZCS navigation subroutines. All variables are REAL*8 except IERR.

ALTCOR  The altitude correction (R+h)/R, where R is the radius of the earth and h is the orbital altitude of the satellite. Supplied by the main or calling program.

IERR  This is a logical variable which when true enables error trace printouts at the terminal. Supplied by the main or calling program. LOGICAL*2

PERIOD  The orbital period of the satellite in seconds. Supplied by the main or calling program.

PITCH  The state of rotation of the satellite about the Y axis in degrees. Supplied by the main or calling program.

ROLL  The state of rotation of the satellite about the X axis in degrees. Supplied by the main or calling program.
The trackline bearing to the pixel in radians. Returned by CZSUBA.

The earth surface distance from the G.P. to the pixel in radians. Returned by CZSUBA.

The effective scan angle (as modified by tilt) in radians. Returned by CZSUBA.

The orbital travel time of the satellite between two points in seconds. For example the time for satellite transit from the equator to the current G.P. Supplied or returned depending on subroutine.

The tilt angle of the CZCS scan view in degrees. This is as read from the satellite (or double the tilt angle of the mirror shaft, Tau). Supplied by the main or calling program.

The trackline equatorial inclination angle, 9.28 deg west of north.

The latitude of the pixel in decimal degrees. Supplied or returned. Or, the new latitude in CZSUB1; returned.

The latitude of the G.P. in decimal degrees. Supplied or returned. Or, the input latitude in CZSUB1.

The longitude of the pixel in decimal degrees. Supplied or returned. The return longitude in CZSUB1.

The longitude of the G.P. in decimal degrees. Supplied or returned. The input longitude in CZSUB1.

The longitude of equatorial crossing in decimal degrees. supplied or returned.

The mirror scan angle in degrees. Supplied by main or calling program.

The state of rotation of the satellite about the Z axis in degrees. Supplied by the main or calling program.

Note that while the angular variables are supplied or returned in degrees, the internal computer computations are performed in radians. These angular variables are converted in the subroutines and then reconverted before return. The exception to this is CZSUBA whose call list contains radians. Variables which start with an X are in degrees and those with an R
are in radians. For example within CZSUB3, XNU is converted to RNU and XLAT becomes RLAT.

LIST OF SUBPROGRAMS IN FILE "CZSUBS": (CZSUB1 - CZSUBA)

CZSUB1
CZSUB2
CZSUB3
CZSUB4
CZSUB5
CZSUBA

*** END DIRECTORY ***

SUBROUTINE CZSUB1 (XINCLP,PERIOD,XLATO,XLONGO,T,XLAT,XLONG,IERR)

IMPLICIT REAL*8(A-H,0-Z)
REAL*8 PI,PID2,DEGRD,DATAN,DATAN2,DSIN,DCOS,DARCOS,DARSIN,DSQRT
REAL*8 RINCLP,RLATO,RLAM,ALAM,DTAN,DABS,RLAT
LOGICAL IERR

PI = 4.0*DATAN(1.0D0)
DEGRD = PI/180.0

RINCLP = XINCLP*DEGRD /* equatorial inclination
RLATO = XLATO*DEGRD

Calculate trackline inclination at initial G.P.
RLAM = DASIN(DSIN(RINCLP)/DCOS(MLATO))

Calculate degrees trackline traveled in T (fixed earth)
DT = T*360.0/PERIOD*DEGRD

Calculate new G.P. latitude
X = DCOS(DT)*DSIN(MLATO)+DSIN(DT)*DCOS(MLATO)*DCOS(ROLAM)
RLAT = DASIN(X)

XLAT = RLAT/DEGRD
C Calculate delta longitude
RLAM = DASIN(DSIN(RINCLO)/DCOS(RLAT)*DSIN(DT))
DLAM = RLAM/DEGRD
C
C New longitude = old long + del lon + earth rotation
XLONG = XLONGO + DLAM + T*4.167E-3
C
IF(IERR) PRINT 2000,XLATO ,XLONGO ,XLAT ,XLONG ,DLAM ,T
2000 FORMAT( 'CZSUB1 - XLATO ,XLONGO ,XLAT ,XLONG ,DLAM ,T = ',/', *
* 1P6G13.6)
RETURN
C
*** END SUBROUTINE CZSUB1 ***
END
C$
Q
*****************************************************************
C CZSUB2 - CZCS Navigation Subr #2
C Given the CZCS G.P. latitude, longitude, tilt, and scan angle,
C this subroutine will return the pixel latitude and longitude.
C
22 July 1981, W. Wilson, Visibility Laboratory,
Scripps Institution of Oceanography.
*****************************************************************
C
SUBROUTINE CZSUB2(XINCLP,ALTCOR,XLATO ,XLONGO,TILT,XNU,XLAT, *
* XLONG,PITCH,ROLL,YAW,IERR)
C
IMPLICIT REAL*8(A-H,0-Z)
REAL*8 PI ,PID2,DEGRD
REAL*8 RINCLP,RLATO ,RINCLO ,RPSIP,RPSI,RTH,X,RLAT,DLAM
REAL*8 RTHS
C
LOGICAL IERR
C
PI = 4.0*DATAN(1.0D0)
DEGRD = PI/180.0
C
IF(IERR) PRINT 2000
2000 FORMAT( ' ENTER CZSUB2' )
C
Get Psi and Theta from CZSUBA
CALL CZSUBA(ALTCOR,TILT,XNU,RPSI,RTHS,RTH,PITCH,ROLL,YAW,IERR)
C
RINCLP = XINCLP*DEGRD
RLATO = XLATO*DEGRD
C
Calculate trackline inclination at G.P. latitude
RINCLO = DASIN(DSIN(RINCLP)/DCOS(RLATO))
C
Calculate true bearing to pixel
RPSIP = RPSI - RINCLO
Calculate pixel latitude
\[
X = \text{DSIN}(RLATO) \times \text{DCOS}(RTH) + \text{DCOS}(RLATO) \times \text{DSIN}(RTH) \times \text{DCOS}(RPSIP)
\]
\[
RLAT = \text{DASIN}(X)
\]
\[
XLAT = RLAT/\text{DEGRD} \quad /* \text{convert back to degrees}\
\]

Calculate delta longitude
\[
X = \text{DSIN}(RPSIP) / \text{DCOS}(RLAT) \times \text{DSIN}(RTH)
\]
\[
DLAM = \text{DASIN}(X)
\]
\[
XDLAM = DLAM/\text{DEGRD}
\]

Calculate pixel longitude
\[
XLONG = XLONGO - XDLAM
\]

PSIP = RPSIP/DEGRD \quad /* \text{convert back to degrees}

TH = RTH/DEGRD

IF(IERR) PRINT 2003,PSIP,XLAT,XDLAM

2003 FORMAT(' PSIP,XLAT,XDLAM = ',1P4G13.6)

RETURN

*** END SUBROUTINE CZSUB2 ***

END

******************************************************************************

SUBROUTINE CZSUB3
This subroutine returns the Latitude and Longitude of the Ground Point of the Satellite. The input variables are the Latitude and Longitude, Tilt and Scan Angle of a Pixel, and the Roll, Pitch, and Yaw, Satellite altitude factor, and equatorial trackline inclination angle of the Satellite.


******************************************************************************

SUBROUTINE CZSUB3(XINCLP,ALTCOR,XLAT,XLONG,TILT,XNU,XLATO, XLONGO,PITCH,ROLL,YAW,IERR)

IMPLICIT REAL*8(A-H,O-Z)
REAL*8 PI,PID2,DEGRD
REAL*8 RPSI,RTH,RLAT,RINCLP,A,B,C,D,AB,XD,X,XP,X1,X2
REAL*8 RLATO1,RLATO2,RLATO,RINCLO,RPSIP,DLAM
REAL*8 RTHS
LOGICAL IERR

PI = 4.0*D\text{ATAN}(1.0D0)
DEGRD = PI/180.0 \quad /* \text{Degrees-Radians conv}

IF(IERR) PRINT 2000

2000 FORMAT(' ENTER CZSUB3')

CALL CZSUBA(ALTCOR,TILT,XNU,RPSI,RTHS,RTH,PITCH,ROLL,YAW,IERR)
SET UP QUADRATIC VARIABLES FROM CZCS ANGULAR COMPONENTS.

See documentation for derivation.

A = DSIN(RLAT) - DSIN(RTH)*DSIN(RPSI)*DSIN(RINCLP)
B = DCOS(RTH)
C = DSIN(RTH)*DCOS(RPSI)
D = DCOS(RINCLP)**2

AB = A*B /* Calculate intermediate vals
XD = B**2 + C**2
IF(IERR) PRINT 2001,A,B,C,D,XD,AB
X = AB**2 - XD*(A**2-D*C**2)
XP = 0.0
IF(X.GT.1.E-10) XP = DSQRT(X)
2001 FORMAT(' A,B,C,D,XD,AB = ',1P6G13.6)

XI = (AB + XP)/XD /* The +/- values from the
X2 = (AB - XP)/XD /* Quadratic.
2005 FORMAT(' X,X1,X2=',1P3G13.6)

RLAT01 = DASIN(X1)
RLAT02 = DASIN(X2)
IF(IERR) PRINT 2005,RLAT01,RLAT02
2006 FORMAT(' RLAT01,RLAT02=',1P2G13.6)

C
C If the tilt is positive choose the negative quad. component and if negative the positive.
C
RLATO = RLAT02
IF(TILT.LT.0.0) RLATO = RLAT01
XLATO = RLATO/DEGRD

C
C Calculate true bearing to pixel
RINCLO = DASIN(DSIN(RINCLP)/DCOS(RLAT))
RPSIP = RPSI - RINCLO
2002 FORMAT(' RPSIP,RTH,RLAT=',1P3G13.6)

C
C Calculate longitude difference G.P. to Pix
X = DSIN(RPSIP)*DSIN(RTH)/DCOS(RLAT)
XLAM = DLAM/DEGRD
XLONGO = XLONG + XLAM /* Calc G.P. Longitude

C
C IF(IERR) PRINT 2003,RLAT01,RLAT02,RLAT02,DLONG = ',1P4G13.6)
PSIP = RPSIP/DEGRD
IF(IERR) PRINT 2004,PSIP,XLATO,XLAM
2004 FORMAT(' PSIP,XLAT,XDLAM = ',1P4G13.6)
RETURN
C
*** END SUBROUTINE CZSUB3 ***
C
*******************************************************************
C CZSUB4 - CZCS Navigation Subr #4
C Given a satellite G.P. latitude and longitude,
C this subroutine calculates the longitude of equatorial crossing,
C and the satellite travel time from the equator to the G.P.
C
22 July 1981, W. Wilson, Visibility Laboratory,
Scripp's Institution of Oceanography.

*******************************************************************
C
SUBROUTINE CZSUB4 (XINCLP,PERIOD,XLATO,XLONGO,XLONGP,T,IERR)
IMPLICIT REAL*8(A-H,O-Z)
C
REAL*8 PI,PID2,DEGRD,DATAN,DATAN2,DSIN,DCOS,DARCOS,DARSIN,DSQRT
REAL*8 RINCLP,RLATO,RLAM,RT,DTAN,DABS,DT
LOGICAL IERR
C
PI = 4.0*DATAN(1.0D0)
DEGRD = PI/180.0
C
RINCLP = XINCLP*DEGRD
RLATO = XLATO*DEGRD
C
Calculate the delta longitude
RLAM = DASIN(DTAN(RLATO)*DTAN(RINCLP))
C
Calculate the degrees traveled and transit time
RT = DASIN(DSIN(RLATO)/DCOS(RINCLP))
DT = RT/DEGRD
T = DT*PERIOD/360.0
C
Calculate the equatorial crossing longitude
DLAM = RLAM/DEGRD
XLONGP = XLONGO - DLAM - T*4.167E-3
C
IF(IERR) PRINT 2000,XLATO,XLONGO,XLONGP,DT,DLAM,T
2000 FORMAT(' CZSUB4 - XLATO,XLONGO,XLONGP,DT,DLAM,T = ',1P6G13.6)
C
RETURN
SUBROUTINE CZSUB5(XINCLP, ALTCOR, PERIOD, XLONGP, XLAT, XLONG, TILT, 
* XLATO, XLONGO, T, XNU, PITCH, ROLL, YAW, IERR)

IMPLICIT REAL*8(A-H,O-Z)
LOGICAL IERR

XL = 0.0  
XH = 1969.
ITER = 0

Start with a known pixel lat-lon ........

10 CONTINUE
XM = (XL+XH)/2.0  
XNU = -39.36 + (XM-1.0)*0.04  

Go calculate a coresponding G.P. lat-lon

CALL CZSUB3 (XINCLP, ALTCOR, XLAT, XLONG, TILT, XNU, XLATO, 
* XLONGO, PITCH, ROLL, YAW, IERR)

Go find the estimated G.P.'s equatorial crossing lon

CALL CZSUB4(XINCLP, PERIOD, XLATO, XLONGO, XLONGQ, T, IERR)

Compare estimated eq. lon with input eq. lon

DIF = XLONGO - XLONGP
IF(DABS(DIF).LT..00028) GO TO 100  
/* good - go return
ITER = ITER + 1
IF(ITER.GT.20) GO TO 200  
/* won't work - quit

22 July 1981, W. Wilson, Visibility Laboratory, 
Scripp's Institution of Oceanography.
C IF(DIF.GT.0.0) XH = XM /* adjust scan limits
C IF(DIF.LT.0.0) XL = XM /* for next try
C IF(IERR) PRINT 2000,XM,XNU,XLATO,XLONGO,XLONGP,XLONGQ,DIF
C 2000 FORMAT(' CZSUB5 = XM,XNU,XLATO,XLONGO,XLONGP,XLONGQ,DIF =',
* /,F7.1,F8.2,1P6G11.5)
C GO TO 10 /* go try again
C 100 CONTINUE
C IF(IERR) PRINT 2000,XM,XNU,XLATO,XLONGO,XLONGP,XLONGQ,DIF
C RETURN
C 200 CONTINUE
C PRINT 2001
C 2001 FORMAT(' FAILED TO CONVERGED - PROBABLY OUTSIDE IMAGE')
C XNU = 9999.
C RETURN
C *** END SUBROUTINE CZSUB5 ***
C
C*************************************************************************
C CZSUBA - CZCS Navigation subroutine
C This is an internal subroutine called by several of the other CZCS navigation subroutines. Given the tilt, scan angle, roll, pitch, and yaw, this routine calculates the trackline relative bearing to the pixel, the effective scan angle, and the earth surface distance (in radians) from the satellite G.P. to the pixel.
C
C*************************************************************************
C
C SUBROUTINE CZSUBA(ALTOR,TILT,XNU,RPSI,RTHS,RTH,PITCH,ROLL,YAW * ,IERA)
C
C IMPLICIT REAL*8(A-H,O-Z)
C REAL*8 PI,PID2,DEGRD,I ROOT
C REAL*8 PI3D2,RPSI,RTH,RNU,RTHS,RTILT
C
C LOGICAL IERR
C
C PID2 = DATAN(1.0D0)*2.0
C PI = PID2*2.0 /* calculate pi
C PI3D2 = PID2*3.0
C DEGRD = PI/180.0 /* degree - radian conversion
C IF(IERR) PRINT 2000,ALTOR,TILT,XNU
2000 FORMAT(' ENTER CZSUBA, ALTCOR,TILT,NU = ', 3F8.3)
RNU = XNU*DEGRD
T = TILT/2.0
RT = T*DEGRD
IF(TILT.NE.0.0) GO TO 1
RPSI = PI/2
IF(XNU.LT.0.0) RPSI = PI3D2
RTHS = DABS(RNU)
GO TO 2
1 CONTINUE
IF(IERR) PRINT 3001,RT,RNU
3001 FORMAT(' 1', ' RT,RNU', 1P3G13.6)
C
C Calculate Theta-n and Phi-n
C
IROOT = 1.0D0/ DSQRT(2.0D0)
RTHR = 2.*DACOS(IROOT*(DSIN(RT)*DCOS(RNU)+DCOS(RT)))
RPHIM = DATAN(DSIN(RNU)/((DSIN(RT)-DCOS(RT)*DCOS(RNU)))+PI)
IF(IERR) PRINT 3002,RTHM,RPHIM,RTHR
3002 FORMAT(' 2', ' RTHM,RPHIM,RTHR', 1P3G13.6)
C
C Calculate Theta and Phi
C
RTHP = 1.0D0/DSQRT(2.0D0)
RPHIP = DATAN(DTAN(RTHR)*DSIN(RPHIM))
IF(TILT.LT.0.0) RPHIP = PI + RPHIP
IF(IERR) PRINT 3003,RTHP,RPHIP
3003 FORMAT(' 3', ' RTHP,RPHIP', 1P2G13.6)
C
IF (ROLL.NE.0. OR. PITCH.NE.0. OR. YAW.NE.0.) GO TO 3
RPSI = RPHIP
RTHS = RTHP
GO TO 2
3 CONTINUE
C
C Correct for roll pitch and yaw
C
U = DSIN(RTHP)*DCOS(RPHIP)
V = DSIN(RTHP)*DSIN(RPHIP)
W = DCOS(RTHP)
Y = YAW*DEGRD
R = ROLL*DEGRD
P = PITCH*DEGRD
XP = (1.0D0 + Y*R*P)*U + (-Y+R*P)*V + P*W
YP = Y*U + V - R*W
ZP = (-P+Y*R)*U + (-P*Y+R)*V + W
IF(IERR) PRINT 3004,U,V,W,XP,YP,ZP
3004 FORMAT(' 4', ' U,V,W,XP,YP,ZP', 1P6G13.6)
RTHS = DACOS(ZP)
RPSI = DATAN2(YF,XP)
CONTINUE
RTH = DASIN(ALTCOR*DSIN(RTHS)) - RTHS
THS = RTHS/DEGRD
TH = RTH/DEGRD
PSI = RPSI / DEGRD
IF(IERR) PRINT 2001,THS,TH,PSI
2001 FORMAT(' THS,TH,PSI = ',1P3G13.6)
RETURN
*** END SUBROUTINE CZSUBA ***
C
C *** CZCS NAVIGATION PROGRAM ***
C
PROGRAM CZNAV
C
C This program uses the CZCS Navigation Subroutines to perform a variety of CZCS location calculations. A menu of functions is provided, variables are global so that, if iterating, only changing parameters need be reentered. Output is displayed on the terminal and written to an output file 'CZCS.DATA'.
C 22 July 1981, J. Nolten, Visibility Laboratory, Scripps Institution of Oceanography
C
IMPLICIT REAL*8 (A-G,N-Z)
INTEGER*4 PTR,TTY,CHOICE
CHARACTER*80 CHAR
LOGICAL IERR
DATA IERR/.FALSE./,PTR/16/,TTY/1/
C
C /* SETUP
PER = 104.09 /* SATELLITE CONSTANTS
PERIOD = PER*60.
XINCLP = 9.28
ALTCOR = (952. + 6371.)/ 6371.
ALTCOR = 1.1494
REV = 1./.12375
ROLL = 0.
PITCH = 0.
YAW = 0.
TILT = 20.
ZERO = 0.
NADIR = 0.32
C
OPEN (UNIT = PTR,
* FILE = 'CZCS.DATA',
* STATUS = 'UNKNOWN',
* FORM = 13.6,}

28
* ACCESS = 'SEQUENTIAL',
* FORM = 'UNFORMATTED',
* ERR  = 99)

C
1000 FORMAT (///,15X,'Welcome to the CZCS Navigation program.',/)
1010 FORMAT (5X,'This program provides a variety of CZCS calculations',
* /,selectable from the menu to follow. Besides the terminal,',
* /,'input and output are written to file "CZCS.DATA".',/)
1020 FORMAT (5X,'Note: ROLL, PITCH, and YAW are initialized to zero,',
* /,13X,'and TILT is initialized to +20.',/)
1030 FORMAT (5X,'Please enter Date and/or any information you would',/,'like included as header on your output file. (80 char. avail)')
1040 FORMAT (A)
WRITE (TTY,1000)
WRITE (TTY,1010)
WRITE (TTY,1020)
WRITE (TTY,1030)
READ (TTY,1040) CHAR
2000 FORMAT (///,15X,'CZCS Navigation Calculations',/)
2010 FORMAT (2X,A,//)
2020 FORMAT (5X ,50('-') ,/)
WRITE (PTR,2000)
WRITE (PTR,2010) CHAR
WRITE (PTR,1020)
WRITE (PTR,2020)

C
/* MAIN LOOP

10 CONTINUE
1050 FORMAT (//,20X,'MENU',/)
1055 FORMAT (' Angle Conventions: entry and output in DDD.MMmm',/,'North and West positive',/)
1060 FORMAT (' 1: Enter Pixel Lat-Lon, X-Y coords, get G.P.',/,'Lat-Lon, Equator data.',/)
1061 FORMAT (' 2: Enter G.P. Lat-Lon, Pixel #; get Pixel Lat-Lon.',/)
1062 FORMAT (' 3: Enter Pixel Lat-Lon, X-Y coords, second Pixel X-Y',/)
1063 FORMAT (' /,8X,'get second Pixel Lat-Lon.',/)
1064 FORMAT (' 4: Enter Equatorial crossing Longitude, Time',/)
1065 FORMAT (' Station Lat-Lon:',/)
1066 FORMAT (' 5: Enter Station Pixel values and Station Time.',/)
1067 FORMAT (' 6: Enter Pixel Lat-Lon, X-Y coords, Station Pixel',/)
1068 FORMAT (' /,8X,'get Station Pixel X-Y coords.',/)
1069 FORMAT (' 7: DegMin-DecDeg and Time-Scan Lines conversions',/)
1070 FORMAT (' /,8X,'Change Roll, Pitch, and Yaw settings.',/)
1071 FORMAT (' 9: QUIT.')
1070 FORMAT (///,'PLEASE ENTER NUMBER OF CALCULATION TO PERFORM.')
WRITE (TTY,1050)
WRITE (TTY,1055)
WRITE (TTY,1060)
WRITE (TTY,1070)
READ (TTY,*) CHOICE

GO TO (20,30,40,50,60,70,80,90,100),CHOICE
GO TO 10

C

4000 FORMAT ('/',' INPUT')
4001 FORMAT (20X,10('-'),/' OUTPUT')
4010 FORMAT (' Pixel Latitude, Longitude:',2F10.4)
4011 FORMAT (' First Pixel: /,5X,'Latitude and Longitude: ',
 2F10.4,/,5X,'X and Y values: ',2I6)
4013 FORMAT (' Tilt = ',F7.1)
4020 FORMAT (' Pixel Number: ',I5,' Tilt: ',F5.1)
4030 FORMAT (' G.P. Latitude, Longitude: ',2F10.4)
4040 FORMAT (' Equatorial crossing Longitude: ',F10.4,/, ' Travel time since equator: ',F7.1,' seconds.')
4050 FORMAT (' Equatorial crossing Longitude: ',F10.4)
4051 FORMAT (' Equatorial crossing time: ',F7.2)
4052 FORMAT (' Station not seen by this Satellite pass.')
4053 FORMAT (' Station Latitude and Longitude: ',2F10.4)
4054 FORMAT (' Optimal equatorial window from ',F9.4,' to ',
  F9.4,')
4055 FORMAT (' Station Pixel X and Y values: ',2I6)
4060 FORMAT (' Second Pixel Latitude, Longitude: ',2F10.4)
4061 FORMAT (' Travel time between scans: ',F7.1,' seconds.')
4062 FORMAT (' Second Pixel X and Y values: ',2I6)
4070 FORMAT (' Time of Station passage: ',F8.3,'
4090 FORMAT (' Roll, Pitch, Yaw changed to: ',3F8.3)
5000 FORMAT ()

C From Pixel info, calculate G.P. info
C
20 CONTINUE

3000 FORMAT ('Enter Pixel Latitude, Longitude, Pixel Number, and Tilt')
WRITE (TTY,3000)
READ (TTY,*) XLAT,XLONG,PIXNO1,TILT
XLAT = DMTOD(XLAT)
XLONG = DMTOD(XLONG)
XNU = -39.04 + 0.04*PIXNO1
CALL CZSUB3(XINCLP,ALTCOR,XLAT,XLONG,TILT,XNU,XLATO,
  XLONGO,PITCH,ROLL,YAW,IERR)
CALL CZSUB4(XINCLP,PERIOD,XLATO,XLONGO,XLONGP,T,IERR)
XLAT = DTODM(XLAT)
XLONG = DTODM(XLONG)
XLATO = DTODM(XLATO)
XLONGO = DTODM(XLONGO)
XLONGP = DTODM(XLONGP)
WRITE (TTY,4000)
WRITE (TTY,4010) XLAT,XLONG
WRITE (TTY,4020) PIXNO1, TILT
WRITE (TTY,4001)
WRITE (TTY,4030) XLATO,XLONGO
WRITE (TTY,4040) XLONGP,T
WRITE (TTY,4002)

WRITE (PTR,4000)
WRITE (PTR,4010) XLAT,XLONG
WRITE (PTR,4020) PIXNO1, TILT
WRITE (PTR,4001)
WRITE (PTR,4030) XLATO,XLONGO
WRITE (PTR,4040) XLONGP ,T
WRITE (PTR,4002)

WRITE (TTY,* ) 'Use RETURN key to continue program when ready.'
READ (TTY,5000)
GO TO 10

C From G.P. Lat-Lon and Pix #, Calculate Pixel Lat-Lon

30 CONTINUE
3010 FORMAT ('Enter G.P. Latitude, Longitude, Pixel #, and Tilt')
WRITE (TTY,3010)
READ (TTY,* ) XLATO,XLONGO,PIXNO1, TILT
XLATO = DMTOD(XLATO)
XLONGO = DMTOD(XLONGO)
XNU = -39.04 + .04*PIXNO1
CALL CZSUB2(XINCLP,ALTCOR,XLATO,XLONGO, TILT,XNU,XLAT, *
XLONG,PITCH,ROLL,YAW,ISERK)
XLAT = DTODM(XLAT)
XLONG = DTODM(XLONG)
XLONGO = DTODM(XLONGO)
XLATO = DTODM(XLATO)
WRITE (TTY,4000)
WRITE (TTY,4030) XLATO,XLONGO
WRITE (TTY,4020) PIXNO1, TILT
WRITE (TTY,4001)
WRITE (TTY,4010) XLAT,XLONG
WRITE (TTY,4002)

WRITE (TTY,* ) 'Use RETURN key to continue program when ready.'
READ (TTY,5000)
GO TO 10

C From Lat-Lon and X-Y for Pixel #1 and X-Y for Pixel #2
   Calculate Lat-Lon for Pixel #2

40 CONTINUE

3020 FORMAT ('Enter Pixel #1 Latitude, Longitude, Pixel and Scan #s')
3021 FORMAT ('Enter Pixel and Scan #s for Pixel #2, and Tilt')
WRITE (TTY,3020)
READ (TTY,*) XLAT,XLONG,PIXN01,SCAN01
XLAT = DMTOD (XLAT)
XLONG = DMTOD (XLONG)
WRITE (TTY,3021)
READ (TTY,*) PIXN02,SCAN02,TILT
XNU = -39.04 + .04*PIXN01
T = (SCAN01-SCAN02)*0.12375
CALL CZSUB3 (XINCLP,ALTCOR,XLAT,XLONG,TILT,XNU,XLATO, *
   XLONGO,PITCH,ROLL,YAW,IERR)
WRITE (TTY,4000)
WRITE (TTY,4011) DTODM (XLAT),DTODM (XLONG),PIXN01,SCAN01
WRITE (PTR,4000)
WRITE (PTR,4011) DTODM (XLAT),DTODM (XLONG),PIXN01,SCAN01
CALL CZSUB1 (XINCLP,PERIOD,XLATO,XLONGO,T,XLAT,XLONG,IERR)
XLATO = XLAT
XLONGO = XLONG
XNU = -39.04 + .04*PIXN02
CALL CZSUB2 (XINCLP,ALTCOR,XLATO,XLONGO,TILT,XNU,XLAT, *
   XLONG,PITCH,ROLL,YAW,IERR)
C
XLAT = DTODM (XLAT)
XLONG = DTODM (XLONG)
XLATO = DTODM (XLATO)
XLONGO = DTODM (XLONGO)
C
WRITE (TTY,4062) PIXN02,SCAN02
WRITE (TTY,4013) TILT
WRITE (TTY,4001)
WRITE (TTY,4060) XLAT,XLONG
WRITE (TTY,4061) T
WRITE (TTY,4002)
WRITE (PTR,4062) PIXN02,SCAN02
WRITE (PTR,4013) TILT
WRITE (PTR,4001)
WRITE (PTR,4060) XLAT,XLONG
WRITE (PTR,4061) T
WRITE (PTR,4002)
C
WRITE (TTY,*) 'Use RETURN key to continue program when ready.'
READ (TTY, 5000)
GO TO 10

C Given Eq crossing lon and Sta. Lat-Lon,
C Calc time of sta passage, scan posit
C
50 CONTINUE

3050 FORMAT ('Enter Equatorial Crossing Longitude, Time (HH.MMM)'
3051 FORMAT ('Enter Station Latitude, Longitude, and Tilt'

WRITE (TTY, 3050)
READ (TTY, *) XLONGP, EQT
XLONGP = DMTOD(XLONGP)
WRITE (TTY, 3051)
READ (TTY, *) XLAT, XLONG, TILT
XLAT = DMTOD(XLAT)
XLONG = DMTOD(XLONG)
CALL C2SUB5(XINCLP, ALT COR, PERIOD, XLONGP, XLAT, XLONG, TILT,
* XLATO, XLONGO, T, XNU, PITCH, ROLL, YAW, IERR)

C
STT = DTODM(DMTOD(EQT) + DMTOD(T/6000.))
XLONGP = DTODM(XLONGP)
XLAT = DTODM(XLAT)
XLONG = DTODM(XLONG)
PIXNOS = (XNU + 39.04)/.04

C
WRITE (TTY, 4000)
WRITE (TTY, 4050) XLAT, XLONG
WRITE (TTY, 4050) XLONGP
WRITE (TTY, 4001)
IF (INTL(XNU).EQ.-9998.) THEN
   WRITE (TTY, 4052)
   GO TO 51
END IF
WRITE (TTY, 4070) STT, PIXNOS

51 CONTINUE

WRITE (TTY, 4002)
WRITE (TTY, 4000)
WRITE (PTR, 4053) XLAT, XLONG
WRITE (PTR, 4050) XLONGP
WRITE (PTR, 4051) EQT
WRITE (PTR, 4001)
IF (INTL(XNU).EQ.-9998.) THEN
   WRITE (PTR, 4052)
   GO TO 52
END IF
WRITE (PTR, 4070) STT, PIXNOS

52 CONTINUE

WRITE (PTR, 4002)
WRITE (TTY,*) 'Use RETURN key to continue program when ready.'
READ (TTY,5000)
GO TO 10

C From Station Latitude, Longitude, Calc Equatorial window

60 CONTINUE
WRITE (TTY,3051)
READ (TTY,*) XLATO,XLONGO,TILT
XLATO = DMTOD(XLATO)
XLONGO = DMTOD(XLONGO)
CALL CZSUB4 (XINCLP,PERIOD,XLATO,XLONGO,XLONGP,T,IERR)
CALL CZSUB2(XINCLP,ALT,ZERO,XLONGP,TILT,35.0D0,XLAT,
* XLONG,PITCH,ROLL,YAW,IERR)
CALL CZSUB2(XINCLP,ALT,ZERO,XLONGP,TILT,-35.0D0,XLAT,
* XLONG,PITCH,ROLL,YAW,IERR)
XLONG = DTODM(XLONG)
XLONGE = DTODM(XLONGE)
XLONGW = DTODM(XLONGW)
XLAT = DTODM(XLAT)
XLATO = DTODM(XLATO)
XLONGO = DTODM(XLONGO)

WRITE (TTY,4000)
WRITE (TTY,4053) XLATO,XLONGO
WRITE (TTY,4001)
WRITE (TTY,4040) XLONGP,T
WRITE (TTY,4054) XLONGE,XLONGW
WRITE (TTY,4002)

WRITE (PTR,4000)
WRITE (PTR,4053) XLATO,XLONGO
WRITE (PTR,4001)
WRITE (PTR,4040) XLONGP,T
WRITE (PTR,4054) XLONGE,XLONGW
WRITE (PTR,4002)

WRITE (TTY,*) 'Use RETURN key to continue program when ready.'
READ (TTY,5000)
GO TO 10

C From reference pixel and station Lat-Lon get sta. X-Y

70 CONTINUE
WRITE (TTY,3020)
READ (TTY,*) XLAT,XLONG,PIXNO1,SCAN01
XLAT = DMTOD(XLAT)
XLONG = DMTOD(XLONG)
WRITE (TTY,3051)
READ (TTY,*) SLAT,SLONG,TILT
SLAT = DMTOD(SLAT)
SLONG = DMTOD(SLONG)
XNU = -39.04 + .04*PIXNO1
   CALL CZSUB3(XINCLP,ALTCOR,XLAT,XLONG,TILT,XNU,XLATO,  
   * XLONGO,PITCH,ROLL,YAW,IERR)
   CALL CZSUB4(XINCLP,PERIOD,XLATO,XLONGO,XLONGP,T,IERR)
T1 = T
   CALL CZSUB5(XINCLP,ALTCOR,PERIOD,XLONGP,SLAT,SLONG,TILT,  
   * XLATO,XLONGO,T,XNU,PITCH,ROLL,YAW,IERR)
PIXNO2 = (XNU + 39.04)/.04
SCANO2 = SCANO1 - (T - T1)/0.12375

C

XLAT = DTODM(XLAT)
XLONG = DTODM(XLONG)
SLAT = DTODM(SLAT)
SLONG = DTODM(SLONG)

WRITE (TTY,4000)
WRITE (TTY,4011) XLAT,XLONG,PIXNO1,SCANO1
WRITE (TTY,4053) SLAT,SLONG
WRITE (TTY,4013) TILT
WRITE (TTY,4001)
IF (INTL(XNU).EQ.-9998) THEN
   WRITE (TTY,4052)
ELSE
   WRITE (TTY,4055) PIXNO2,SCANO2
END IF
WRITE (TTY,4002)

WRITE (PTR,4000)
WRITE (PTR,4011) XLAT,XLONG,PIXNO1,SCANO1
WRITE (PTR,4053) SLAT,SLONG
WRITE (PTR,4013) TILT
WRITE (PTR,4001)
IF (INTL(XNU).EQ.-9998) THEN
   WRITE (PTR,4052)
ELSE
   WRITE (PTR,4055) PIXNO2,SCANO2
END IF
WRITE (PTR,4002)

WRITE (TTY,*) 'Use RETURN key to continue program when ready.'
READ (TTY,5000)
GO TO 10

DegMin-DecDeg and Time-Scan Lines conversions

80 CONTINUE
3080 FORMAT ('Enter value to be converted, space, and identifier:')
3085 FORMAT (T15," L" = Scan lines',/ ,T15," S" = Seconds',
* / ,T15," DM" = Degrees Minutes',/ ,T15," DD" = Decimal Degrees',
* / ,T15," Q" = QUIT')
3083 FORMAT (F7.1,' seconds equals',T15,' scan lines.')
3084 FORMAT (T15,' scan lines equals',F7.1,' seconds.')
3081 FORMAT (F10.4,' degrees.minutes equals',F10.4,' decimal degrees')
3082 FORMAT (F10.4,' decimal degrees equals',F10.4,' degrees.minutes')
IFIRST = 1
81 CONTINUE
WRITE (TTY,3080)
IF (IFIRST.EQ.1) WRITE (TTY,3085)
READ (TTY,1040) CHAR
IF (INDEX(CHAR,'Q').NE.0) GO TO 10
READ (CHAR,*) VAL
IF (INDEX(CHAR,'M').NE.0) THEN
WRITE (TTY,3081) VAL,DMTOD(VAL)
ELSE IF (INDEX(CHAR,'S').NE.0) THEN
WRITE (TTY,3083) VAL,VAL/0.12375
ELSE IF (INDEX(CHAR,'L').NE.0) THEN
WRITE (TTY,3084) VAL,VAL*0.12375
ELSE
WRITE (TTY,3082) VAL,DTODM(VAL)
END IF
WRITE (TTY,4002)
IFIRST = IFIRST + 1
GO TO 81
C
C Change Roll, Pitch, Yaw values
C
90 CONTINUE
3090 FORMAT ('Enter new Roll, Pitch, Yaw values. DECIMAL DEGREES!')
WRITE (TTY,3090)
READ (TTY,*) ROLL,PITCH,YAW
WRITE (TTY,4090) ROLL,PITCH,YAW
WRITE (PTR,4090) ROLL,PITCH,YAW
WRITE (PTR,4002)
C
GO TO 10
C
99 CONTINUE
WRITE (TTY,*) 'ERROR ON FILE OPENING'
STOP 'EXIT CZCS Navigation'
C
100 CONTINUE
ENDFILE (PTR)
CLOSE (PTR)
STOP 'EXIT CZCS Navigation'
END
REAL FUNCTION DMTOD*8(X)
REAL*8 X,P3,P2,DINT,DMOD,DSIGN,DABS
REAL*8 DMTOD

P3 = DABS(X)
P2 = DINT(P3) + DMOD(P3,1.0D0)*100.0/60.0
DMTOD = P2*DSIGN(1.0D0,X)
RETURN
END

REAL FUNCTION DTODM*8(X)
IMPLICIT REAL*8(A-H,O-Z)
REAL*8 P3,P2,DINT,DMOD,X,DSIGN,DABS
P3= DABS(X) + .0000005
P2 = DINT(P3) + DMOD(P3,1.0D0)*60.0/100.0
DTODM = P2*DSIGN(1.0D0,X)
RETURN
END