



# Synergistic soil moisture observation: an interdisciplinary multi-sensor approach to yield improved estimates across scales

Benjamin Fersch  
 Institute of Meteorology and Climate Research (IMK-IFU), Karlsruhe Institute of Technology (KIT), Garmisch-Partenkirchen, Germany  
 Contact: fersch@kit.edu

Thomas Jagdhuber  
 German Aerospace Center (DLR), Oberpfaffenhofen Germany

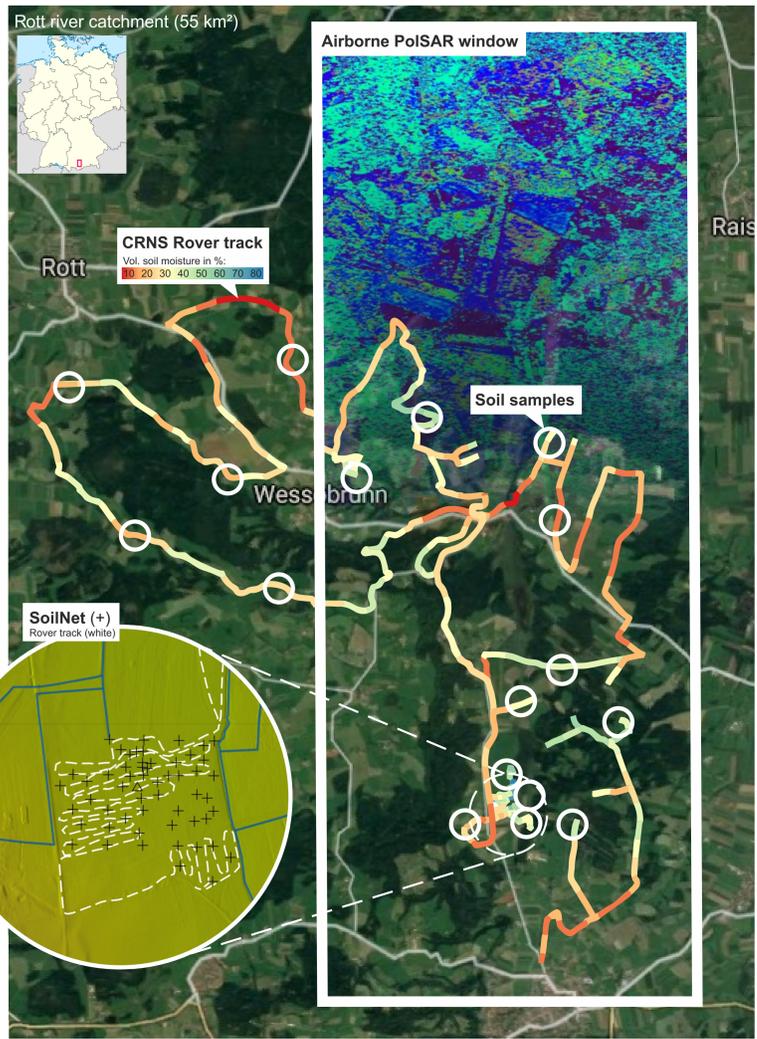
Martin Schrön  
 Helmholtz Centre for Environmental Research (UFZ), Leipzig, Germany

## MOTIVATION

- Soil moisture observation methods differ in extent, spacing, and support.
- A single method for soil moisture retrieval under vegetation cover does often not provide sufficient accuracy (remote sensing methods) or spatial extent (in situ methods).
- How well is the performance of the individual retrieval methods? Do they have potential to assist each other (synergistic approach)?
- The ScaleX campaign 2015 conducted by KIT within the Rott catchment, Germany, provided a great opportunity to combine in situ, car-, and airborne passive and active sensors for soil moisture observation.

## STUDY AREA

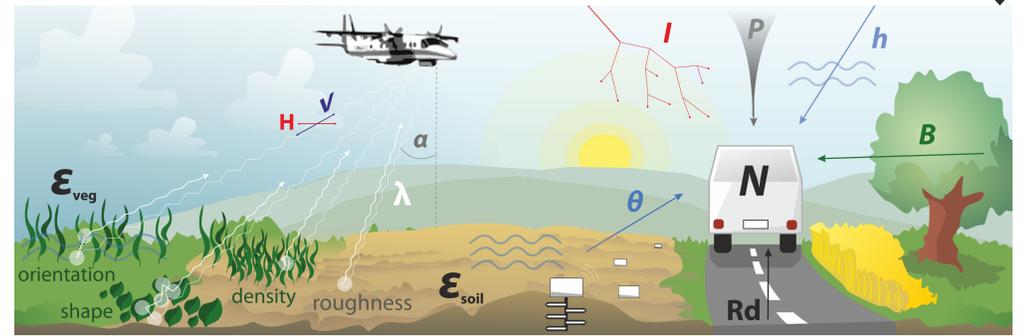
Fig. 1: Overview of location and extent of soil moisture observations used in this study.



## METHODS

	Airborne Polarimetric SAR	Soil Monitoring Network	Cosmic-Ray Neutron Rover
extent	++	--	+
spacing	++	+	o
horizontal support	++	--	+
vertical support	--	++	+
complexity	--	++	o

Fig. 2: The soil moisture observation techniques used in this study: (left) airborne polarimetric SAR, (middle) in situ soil moisture network, and (right) car-borne cosmic-ray neutron sensor. Various steps are required to extract soil moisture information from the integrated signals that are influenced by various environmental factors.



**Polarimetric SAR**  
 based partly on Jagdhuber et al. (2015)  
**NOVEL: grassland vegetation removal** using a grassland-specialized, fully adaptive PolSAR decomposition and inversion for soil moisture

Removal of Vegetation Component and Inversion for Soil Moisture  
 Total Scattering - Vegetation = Ground

**CRNS Rover road-effect correction**  
 based on Schrön et al. (2017)

$$N' = N / C_{road}$$

relative bias  $C_{road} = \frac{N_{road}}{N_{veg}}$

Stone:  $\theta_{veg} = 3\%$   
 Asphalt:  $\theta_{veg} = 12\%$

**CRNS Rover NOVEL: vegetation correction** using the hv-backscatter product from PolSAR.

**B** in units of dB (ranges from -35 to -1)  
 $N'' = N \exp(\alpha B)$

## RESULTS

### 1. CRNS Rover performance benefits from PolSAR backscatter vegetation proxy data

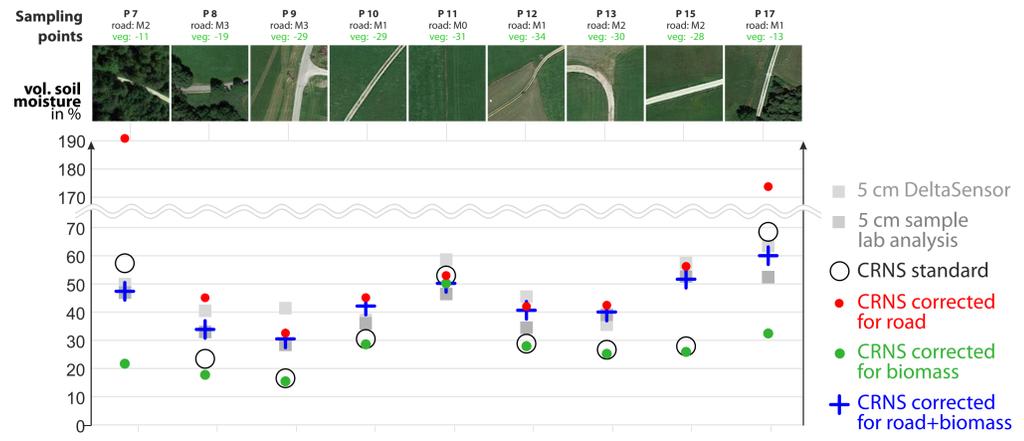


Fig 3: Measured soil moisture from point samples (gray squares) at 9 locations along the rover path. These locations show different road properties (M0–3) and vegetation cover (measured by PolSAR in units of dB). In comparison, soil moisture from CRNS rover using the standard methods (black circles), with road-effect correction (red), with the novel vegetation correction (green), and with both corrections combined (blue crosses).

## RESULTS (cont'd)

### 2. PolSAR vegetation removal algorithm for grass landcover benefits from SoilNet data

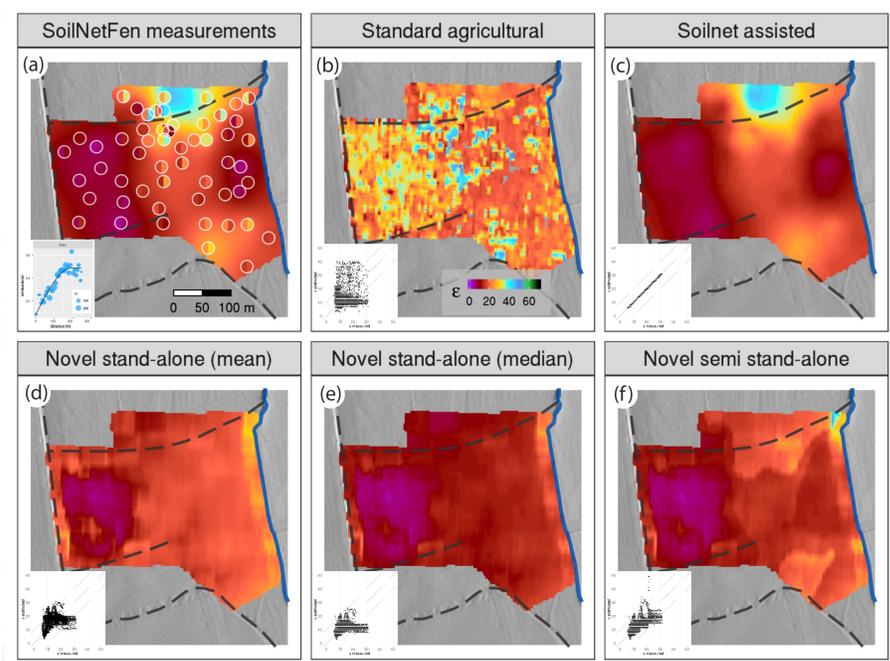


Fig. 4: Comparison of (a) SoilNet-based measurements of surface relative permittivity (real part) in 5 cm depth, with PolSAR-based estimates using (b) the standard approach (Jagdhuber et al. 2015), (c) assisted, and (d-f) (semi-) stand-alone retrieval techniques for moisture estimation below grass covered land.

### 3. CRNS Rover benefits from baseline calibration (N0) using data from the SoilNet

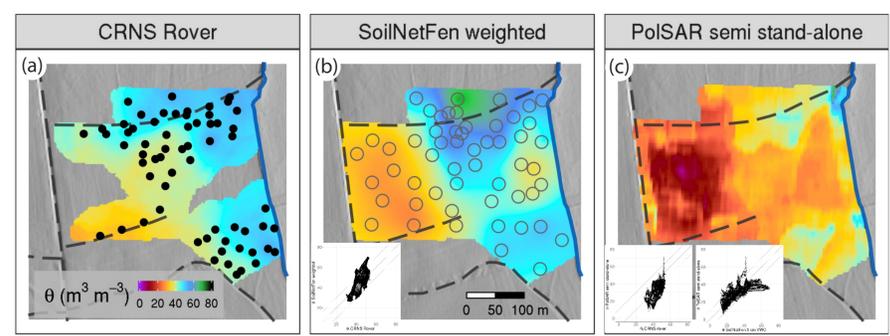


Fig. 5: Comparison of (a) root-zone integrated soil moisture from the CRNS Rover with (b) weighted root-zone estimate from the SoilNet, and (c) the surface soil moisture estimate using the PolSAR semi stand-alone retrieval.

## CONCLUSIONS

- In situ data provides valuable information to calibrate the CRNS Rover and helped to improve the vegetation removal part of the PolSAR decomposition algorithm for grassland.
- The comparison of the 3 individual methods indicates an uncertainty range of approx. ± 10%.
- CRNS Rover performance against local soil samples improved when corrected with vegetation proxy data from PolSAR's hv-backscatter product.
- The synergistic approach has the potential to bridge different scales and to provide reasonable soil moisture observations for the regional scale.

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