

Ionosphere

- 2 main issues:

- dispersion of the signal

- phase errors → beamforming (longer BL) -> See “signal”

- Major issue @ low frequencies (100-350 MHz)

$$\Delta_{ph,f}^{iono} = -\frac{40.3}{f^2} \int N_e dl$$

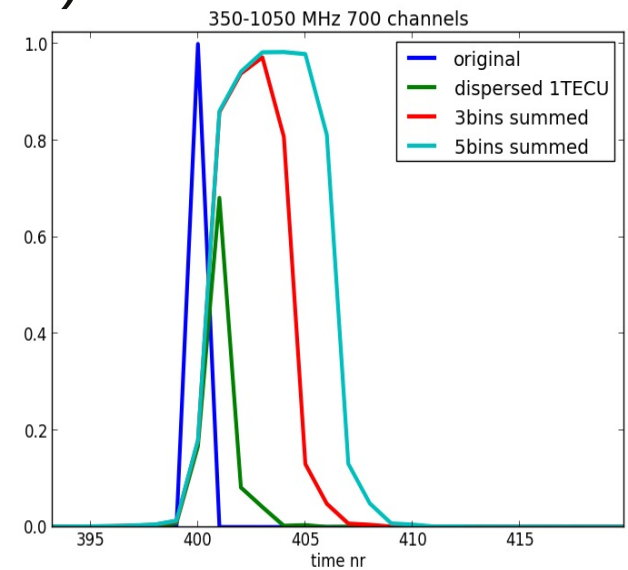
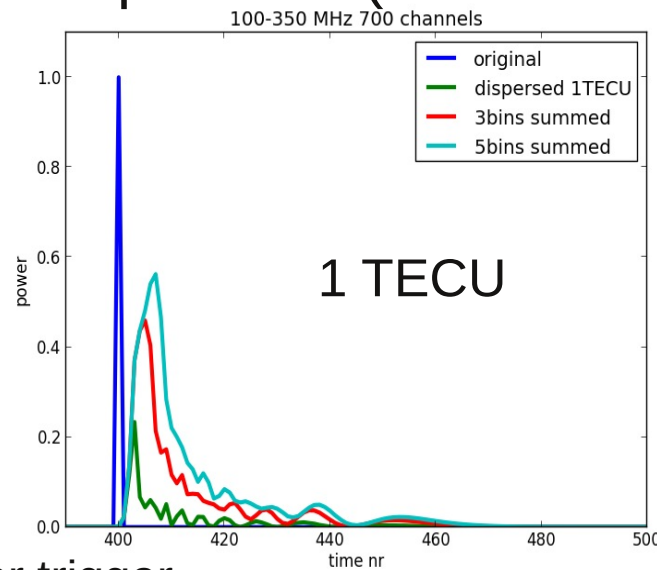
- Dedispersion:

- online:

- Maximize S/N for trigger
 - separate from Earth-based events (Moon reflected)
 - compare dedispersed signal with original (2 signal paths)

- offline:

- better signal reconstruction
 - discriminate between signal and Earth-based/Moon-reflected noise
 - determine trigger efficiency (from error in online applied TEC-values)



Online dedispersion

- Dedisperse phases before trigger:
 - Use range of values for dedispersion (-0.5TECU, mean absolute TEC, +0.5TECU,...)
- Absolute TEC values from:
 - **GPS data**
 - online available on ftp servers:
 - raw data within 30 min, fitted IONEX data: days
 - limited accuracy: ~ 1TECU on final IONEX products
 - contact SKA Polarization working group about placing GPS stations
 - **Useful Software (developed for polarization measurements):**
 - ALBUS (fit TECscreen on GPS data) https://github.com/twillis449/ALBUS_ionosphere/
 - RMextract: IONEX data from ftp servers <https://github.com/maaijke/RMextract>
 - **Faraday Rotation Polarized source:**
 - Lunar Limb polarization:
 - take into account parallactic angle when imaging
 - Difficult for online TEC estimation (?)
 - Certainly worth investigating for offline dedispersion
 - Other polarized calibrators (within FOV?)
 - **Other methods (?):**
 - Parametric models: PIM: <http://www.cpi.com/products/pim.html>
 - Differential Faraday Rotation: $dFR = TEC_1 * B_{||1} - TEC_2 * B_{||2} = dTEC * B_{||1} + TEC * dB_{||}$
 - dTEC/dFR from calibration, $B_{||}$ from Earth Magnetic Field models

