

Imaging, Deconvolution & Image Analysis

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Scientific Analysis of a mm Interferometer Output

mm interferometer output:

Calibrated visibilities in the uv plane (\simeq the Fourier plane).

2 possibilities:

- uv plane analysis (cf. Lecture by A. Castro-Carrizo):
Always better . . . when possible!
(in practice for “simple” sources as point sources or disks)
- Image plane analysis:
 \Rightarrow Mathematical transforms to go from uv to image plane!

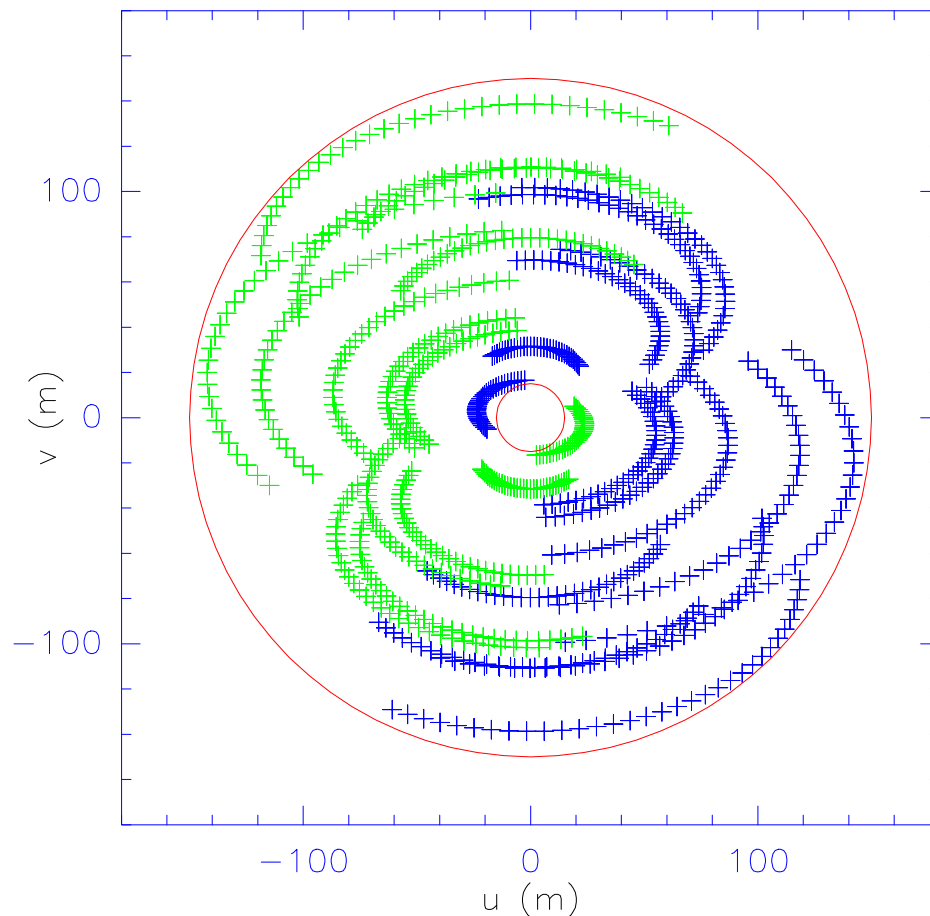
Goal: Understand effects of the imaging process on

- The resolution;
- The field of view (single pointing or mosaicing, cf. Lecture by F. Gueth);
- The reliability of the image;
- The noise level and repartition (cf. lecture by S. Guilloteau).

From Calibrated Visibilities to Images:

I. Comparison Visibilities/Source Fourier Transform

$$V_{ij}(b_{ij}) = 2D \text{ FT} \{ B_{\text{primary}} \cdot I_{\text{source}} \} (b_{ij}) + N$$



- Primary Beam
⇒ Distorted source information.
- Noise ⇒ Sensitivity problems.
- Irregular, limited sampling
⇒ incomplete source information:
 - Support limited at:
 - * High spatial frequency
⇒ limited resolution;
 - * Low spatial frequency ⇒ problem of wide field imaging;
 - Inside the support, incomplete (*i.e.* Nyquist's criterion not respected) sampling ⇒ lost of information.

From Calibrated Visibilities to Images:

II. Effect of Irregular, Limited Sampling

Definitions:

- $V = 2D \text{ FT} \{B_{\text{primary}} \cdot I_{\text{source}}\};$
- Irregular, limited sampling function:
 - $S(u, v) = 1$ at (u, v) points where visibilities are measured;
 - $S(u, v) = 0$ elsewhere;
- $B_{\text{dirty}} = 2D \text{ FT}^{-1} \{S\};$
- $I_{\text{meas}} = 2D \text{ FT}^{-1} \{S \cdot V\}.$

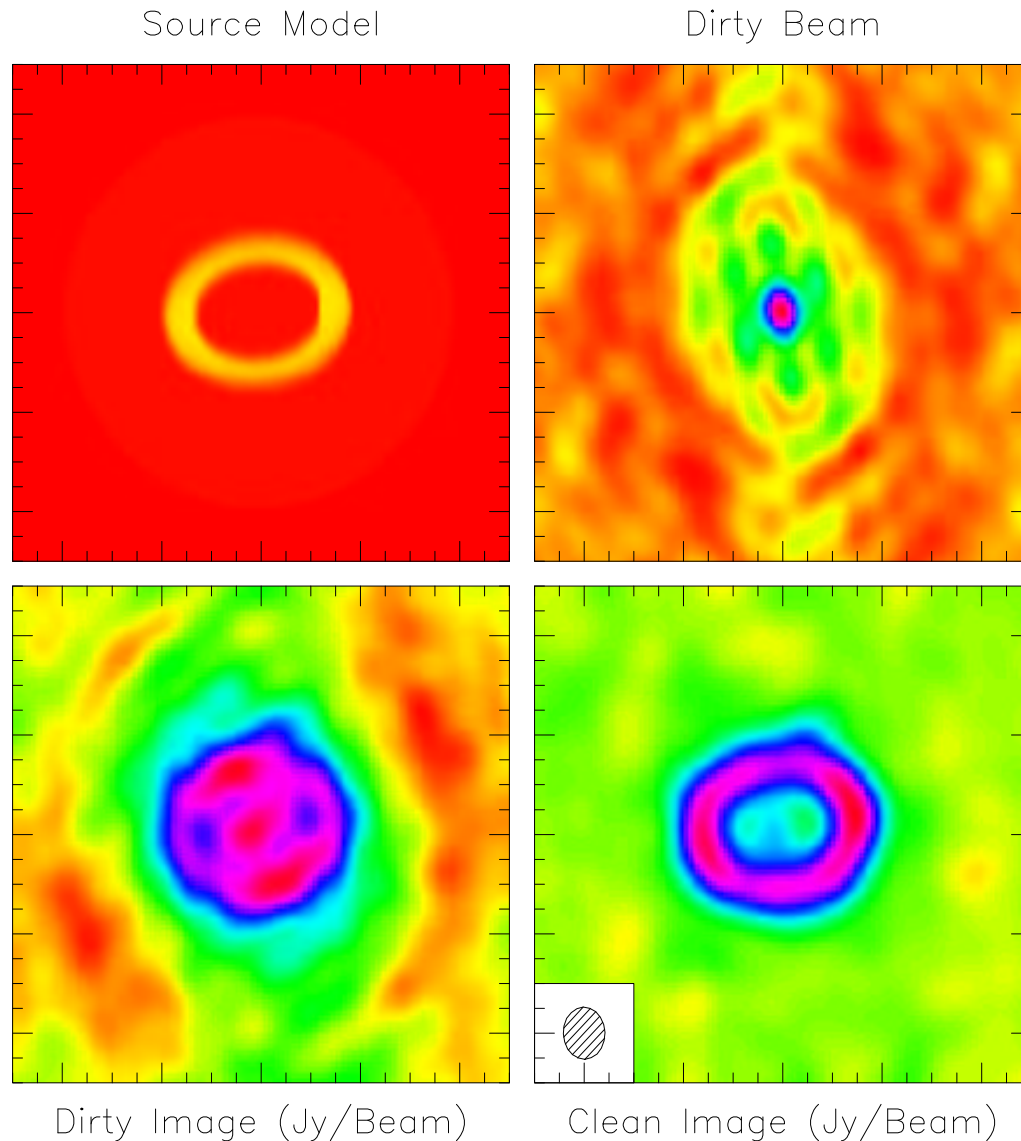
Fourier Transform Property #1:

$$I_{\text{meas}} = B_{\text{dirty}} * \{B_{\text{primary}} \cdot I_{\text{source}}\}.$$

B_{dirty} : Point Spread Function (PSF) of the interferometer
(i.e. if the source is a point, then $I_{\text{meas}} = I_{\text{tot}} \cdot B_{\text{dirty}}$).

From Calibrated Visibilities to Images:

III. Why Deconvolving?



- Difficult to do science on dirty image.
- Deconvolution \Rightarrow a clean image compatible with the sky intensity distribution.

From Calibrated Visibilities to Images:

IV. Summary

Fourier Transform and Deconvolution:
The two key issues in imaging.

Stage	Implementation
Calibrated Visibilities	
↓ Fourier Transform	UV_STAT, UV_MAP
Dirty beam & image	
↓ Deconvolution	HOGBOM, CLARK
Clean beam & image	
↓ Visualization	GO_BIT, GO_VIEW
↓ Image analysis	GO_NOISE, GO_FLUX, GO_MOMENTS
Physical information on your source	

Direct vs. Fast Fourier Transform

Direct FT:

- Advantage: Direct use of the irregular sampling;
- Inconvenient: Slow.

Fast FT:

- Inconvenient: Needs a regular sampling \Rightarrow Gridding;
- Advantage: Quick for images of size $2^M \times 2^N$.

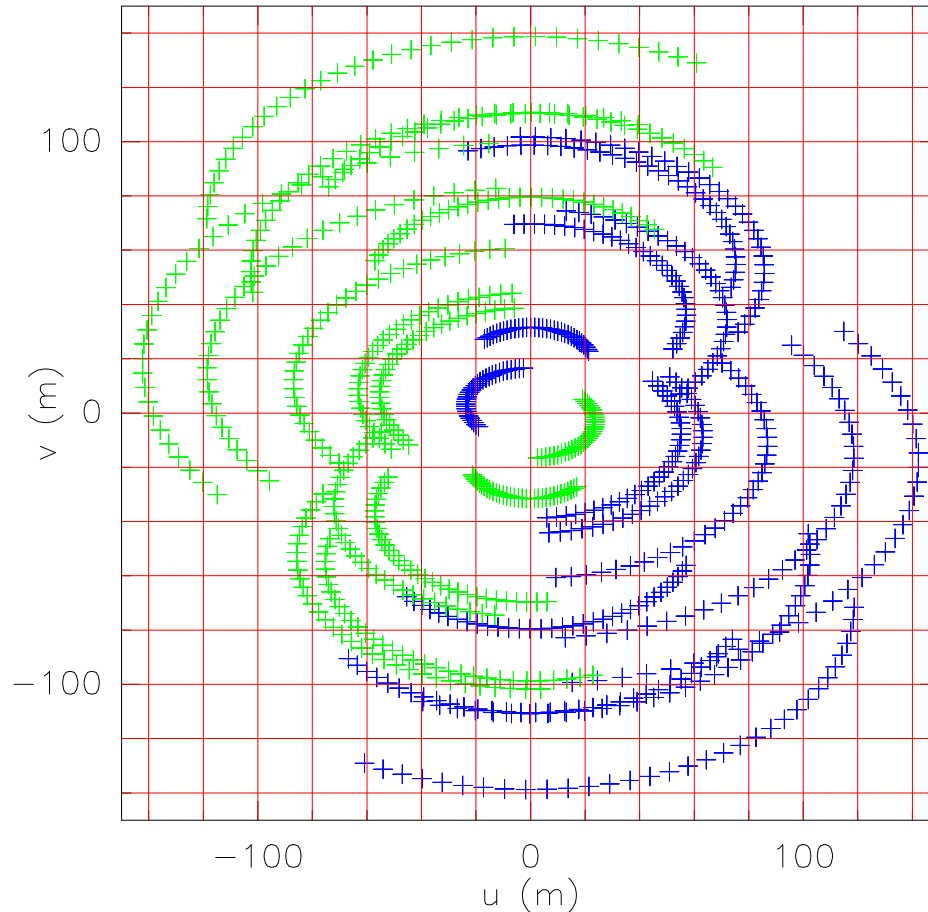
\Rightarrow In practice, everybody use FFT.

From Calibrated Visibilities to Images: Summary

Fourier Transform and Deconvolution:
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Physical information on your source	

Gridding: I. Interpolation Scheme



Convolution because:

- Visibilities = noisy samples of a smooth function.
⇒ Some smoothing is desirable.
- Nearby visibilities are not independent.
 - $V = 2D \text{ FT} \{ B_{\text{primary}} \cdot I_{\text{source}} \}$
 $= \tilde{B}_{\text{primary}} * \tilde{I}_{\text{source}};$
 - $\text{FWHM}(\text{convolution kernel}) < \text{FWHM}(\tilde{B}_{\text{primary}})$
⇒ No real information lost.

Gridding: II. Convolution Equation is Kept Through Gridding

Demonstration:

- $I_{\text{meas}}^{\text{grid}} \xLeftrightarrow[2\text{D FT}] G * (S.V) \Leftrightarrow I_{\text{meas}}^{\text{grid}} = \tilde{G} . (\widetilde{S.V});$
- $B_{\text{dirty}}^{\text{grid}} \xLeftrightarrow[2\text{D FT}] G * S \Leftrightarrow B_{\text{dirty}}^{\text{grid}} = \tilde{G} . \tilde{S};$

$$\Rightarrow I_{\text{meas}} = B_{\text{dirty}} * \{B_{\text{primary}} . I_{\text{source}}\}$$

with $I_{\text{meas}} = I_{\text{meas}}^{\text{grid}} / \tilde{G}$
and $B_{\text{dirty}} = B_{\text{dirty}}^{\text{grid}} / \tilde{G}.$

Remark: Gridding may be hidden in equations but it is still there.
 \Rightarrow Artifacts due to gridding! (cf. next transparencies)

Gridding:

III. Effect of a Regular Sampling (Periodic Replication)

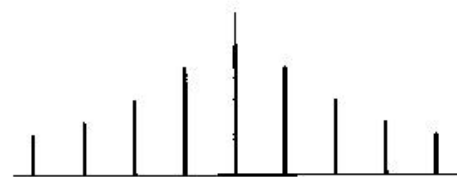
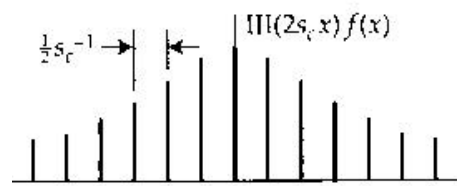
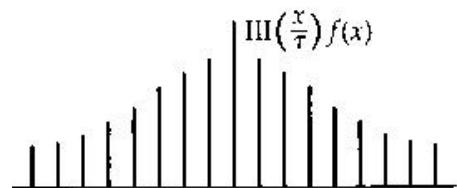
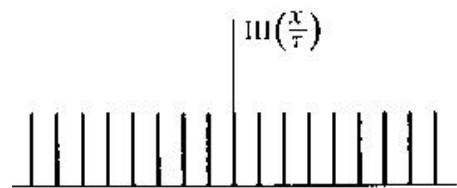
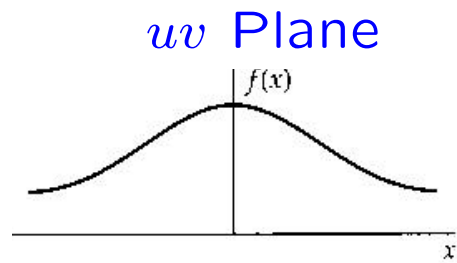
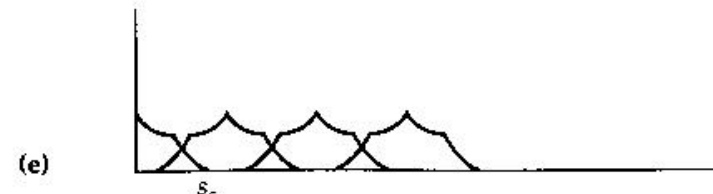
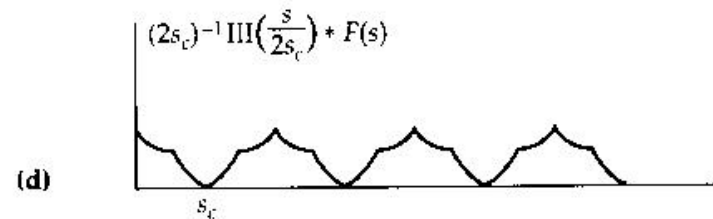
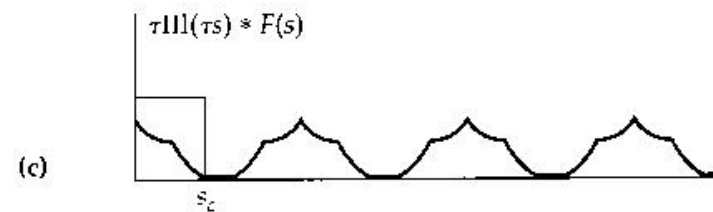


Image Plane



$B_{\text{primary}} \cdot I_{\text{source}}$

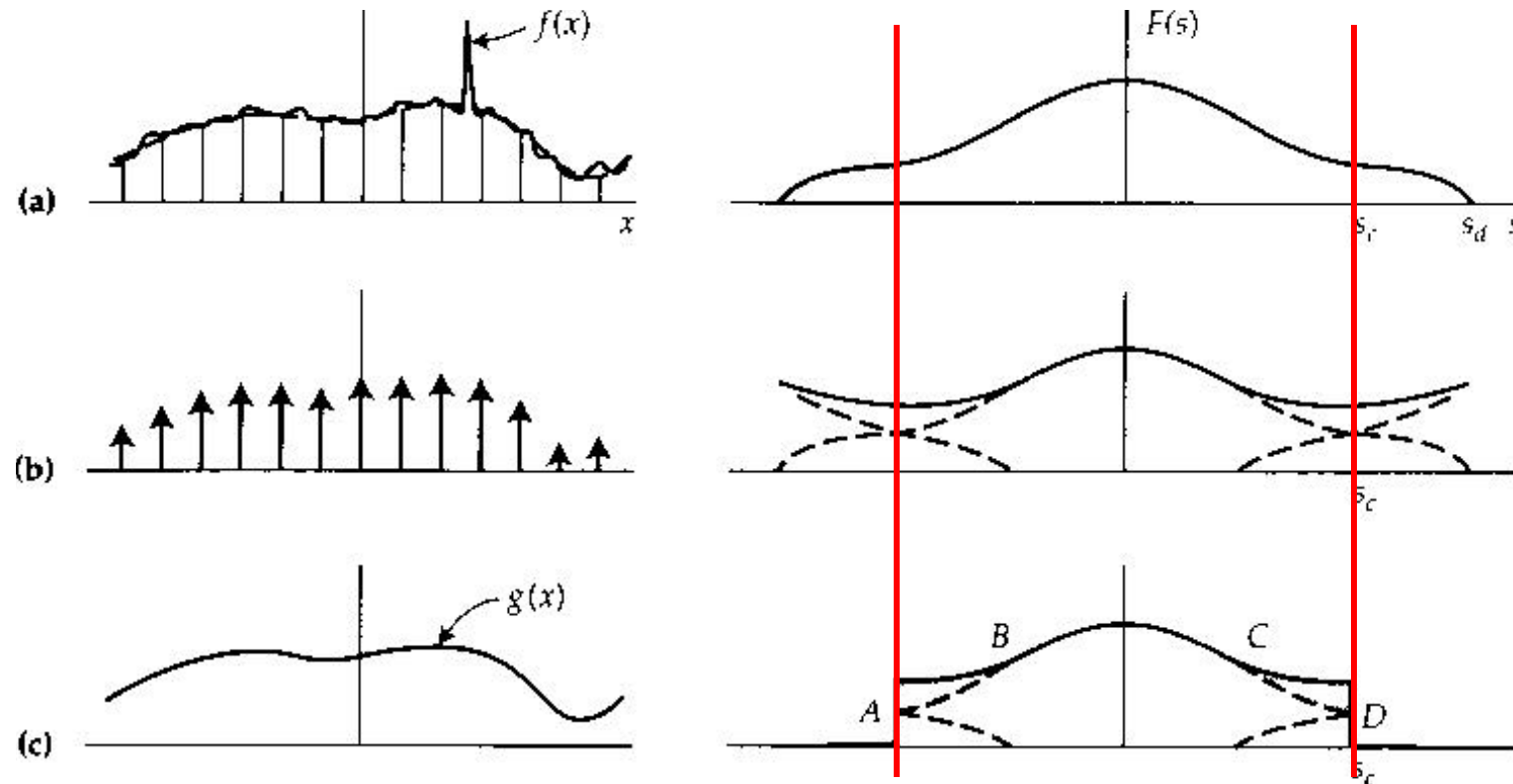
Regular Sampling function

Result for a **fine** sampling

Result for **critical** sampling
(Nyquist's criterion)

Result for a **coarse** sampling

Gridding: III. Effect of a Regular Sampling (Aliasing)



Aliasing = Folding of intensity outside the image size into the image.

⇒ Image size must be large enough.

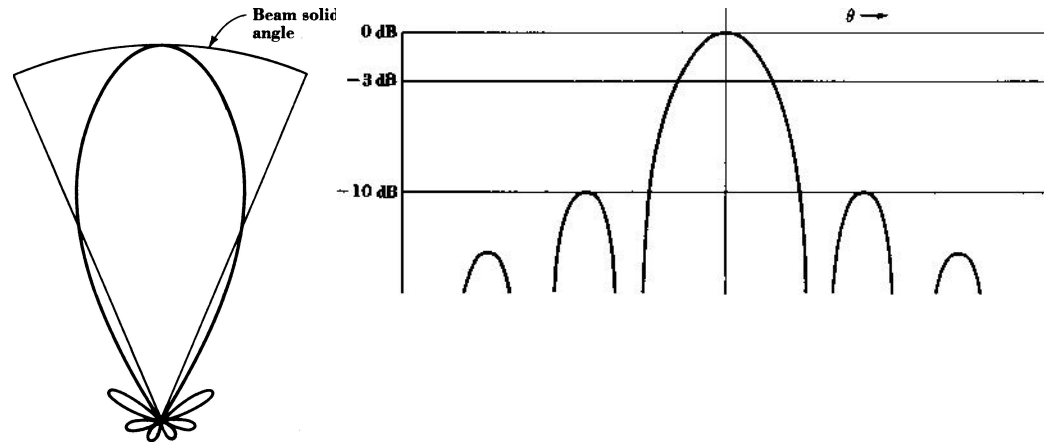
Gridding: IV. Pixel and Image Sizes

Pixel size: Between $1/3$ and $1/4$ of the synthesized beam size (*i.e.* more than the Nyquist's criterion in image plane to ease deconvolution).

Image size:

- = uv plane sampling rate (FT property # 2);
 - Natural resolution in the uv plane: $\tilde{B}_{\text{primary}}$ size;
- ⇒ At least twice the B_{primary} size (*i.e.* Nyquist's criterion in uv plane).

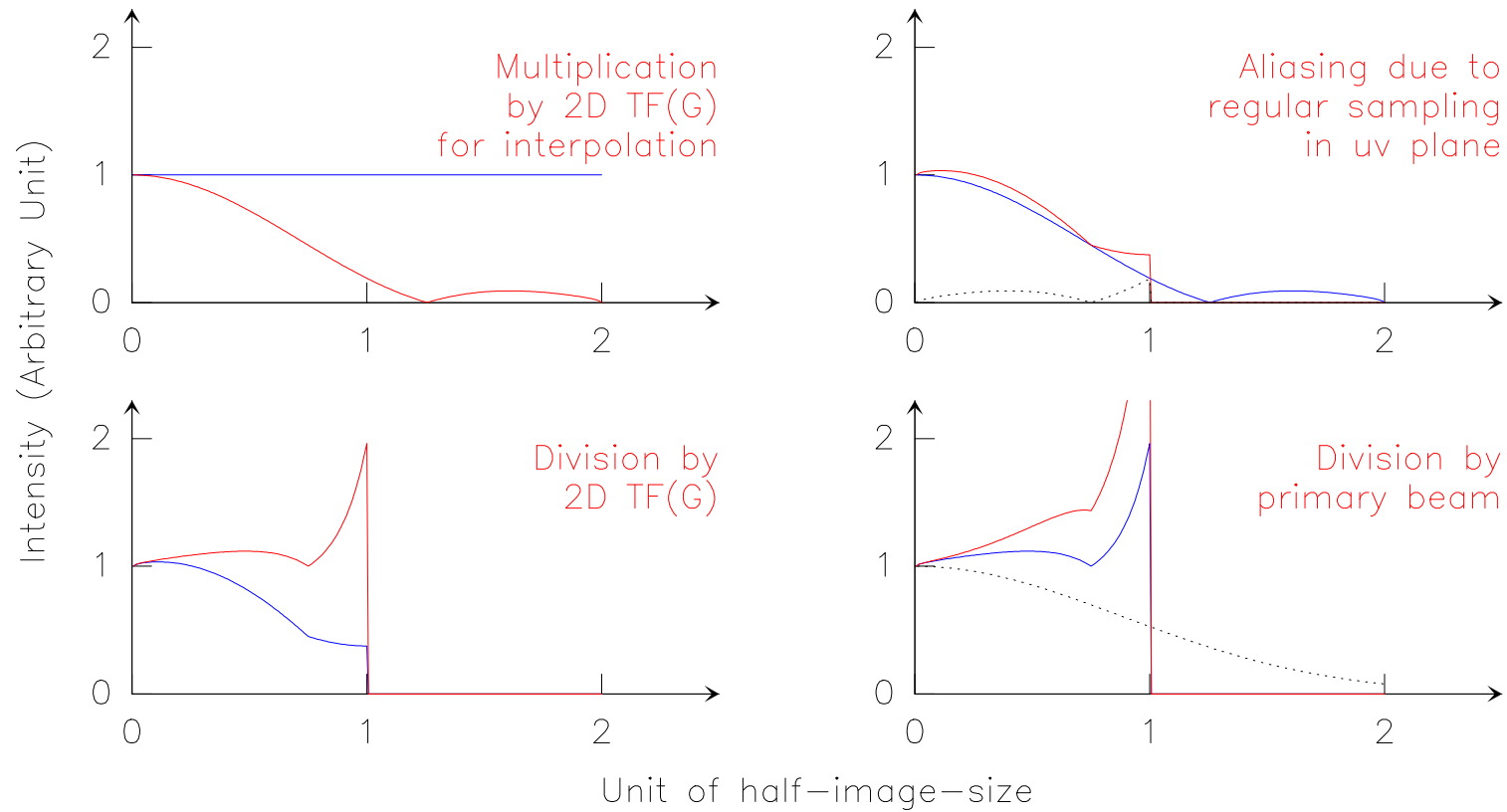
Gridding: V. Bright Sources in B_{primary} Sidelobes



Bright Sources in B_{primary} sidelobes
outside image size will be aliased into image.
 \Rightarrow Spurious source in your image!

Solution: Increase the image size.
(Be careful: only when needed for efficiency reasons!)

Gridding: VI. Noise Distribution



Gridding: VII. Choice of Gridding function

Gridding function must:

- Fall off quickly in image plane (to avoid noise aliasing);
- Fall off quickly in uv plane (to avoid too much smoothing).

⇒ Define a mathematical class of functions: **Spheroidal functions**.

GILDAS implementation: In `UV_MAP`

- Spheroidal functions = Default gridding function;
- Tabulated values are used for speed reasons.

Dirty Beam Shape and Image Quality

$$B_{\text{dirty}} = 2\text{D FT}^{-1} \{S\}.$$

Importance of the Dirty Beam Shape:

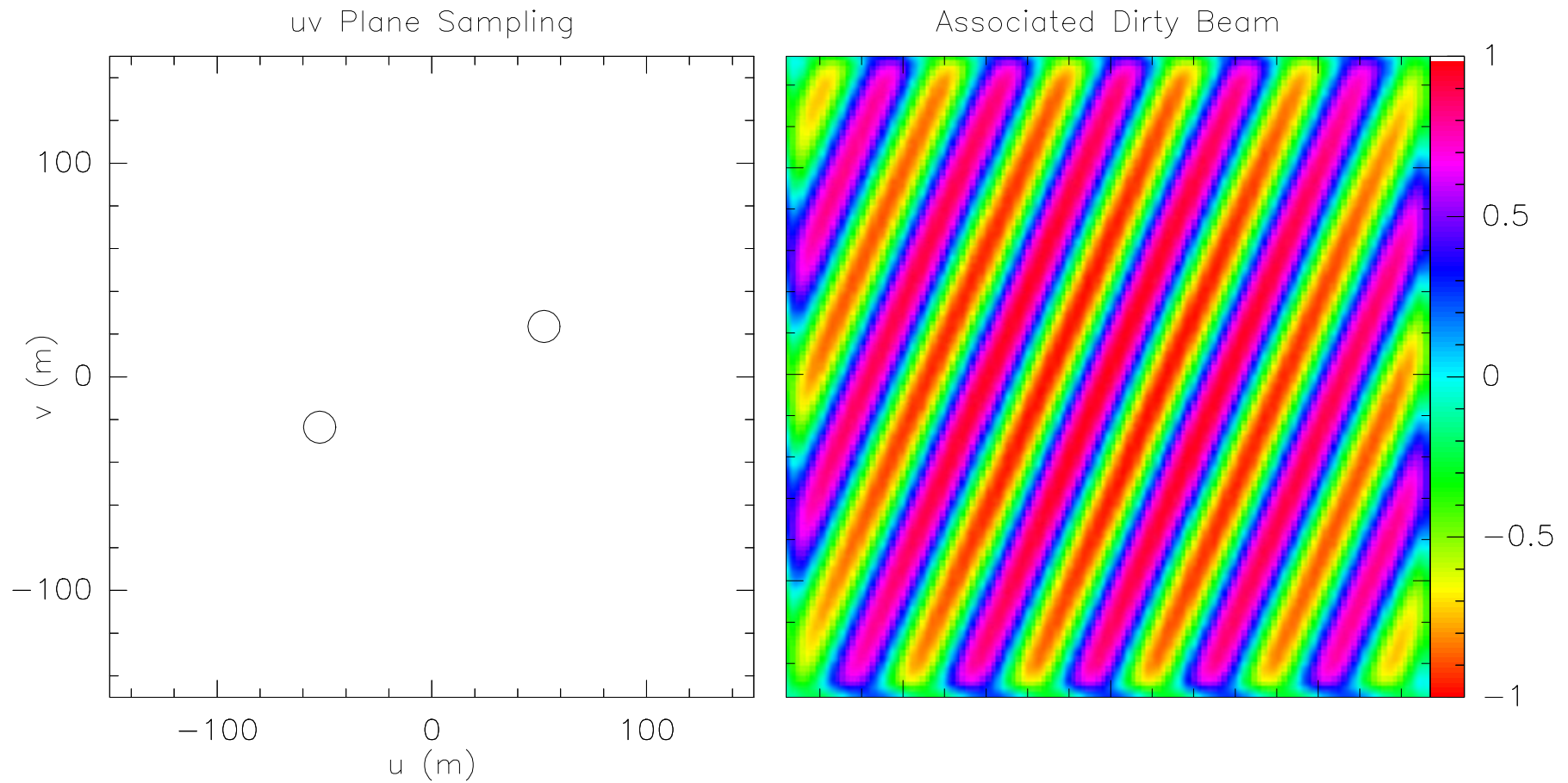
- Deconvolving a dirty image is a delicate stage;
- The closest to a Gaussian B_{dirty} is, the easier the deconvolution;
- Extreme case:
 $B_{\text{dirty}} = \text{Gaussian} \Rightarrow$ No deconvolution needed at all!

Ways to improve (at least change) B_{dirty} shape:

- Increase the number of antenna (costly).
- Change the antenna layout (technically difficult).
- Weight the irregular, limited sampling function S (the only thing you can do in practice).

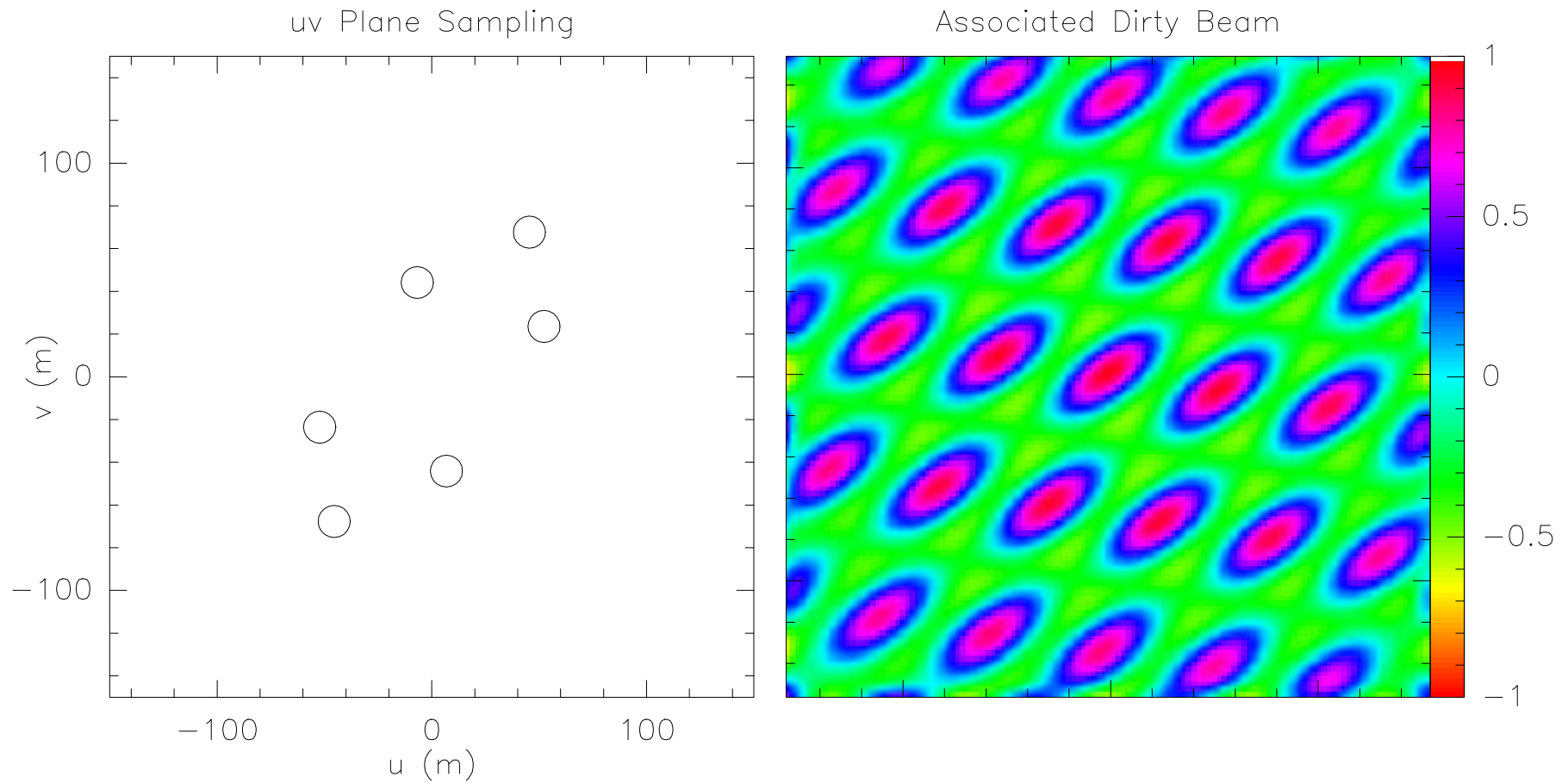
Dirty Beam Shape and Number of Antenna:

2 Antenna



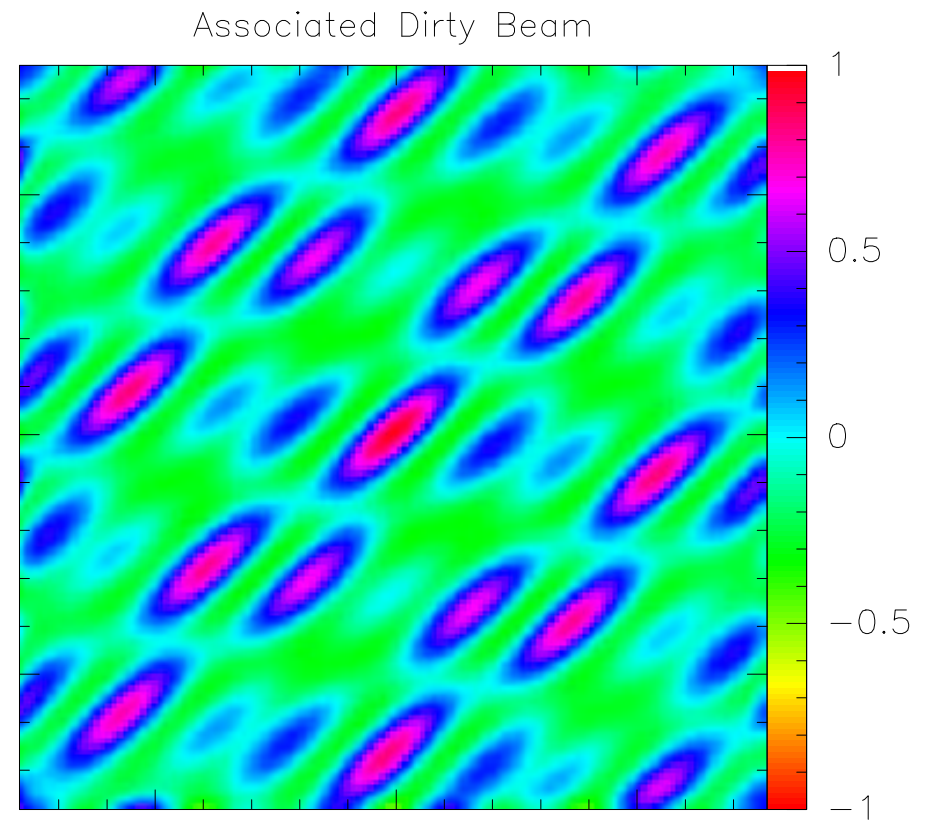
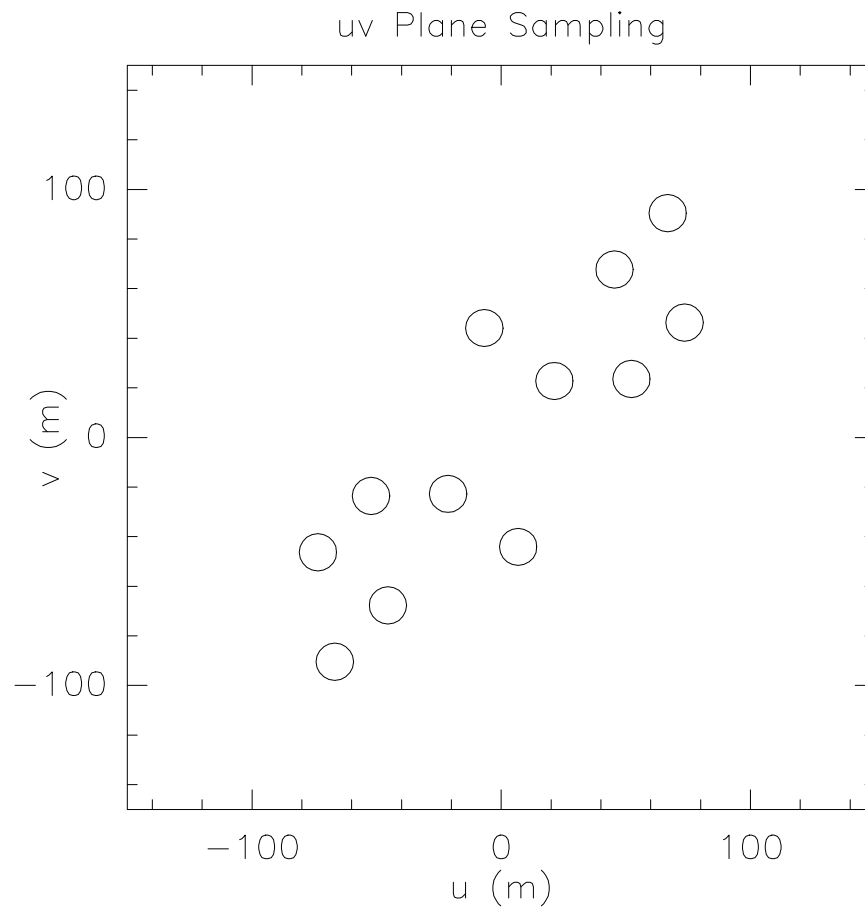
Dirty Beam Shape and Number of Antenna:

3 Antenna



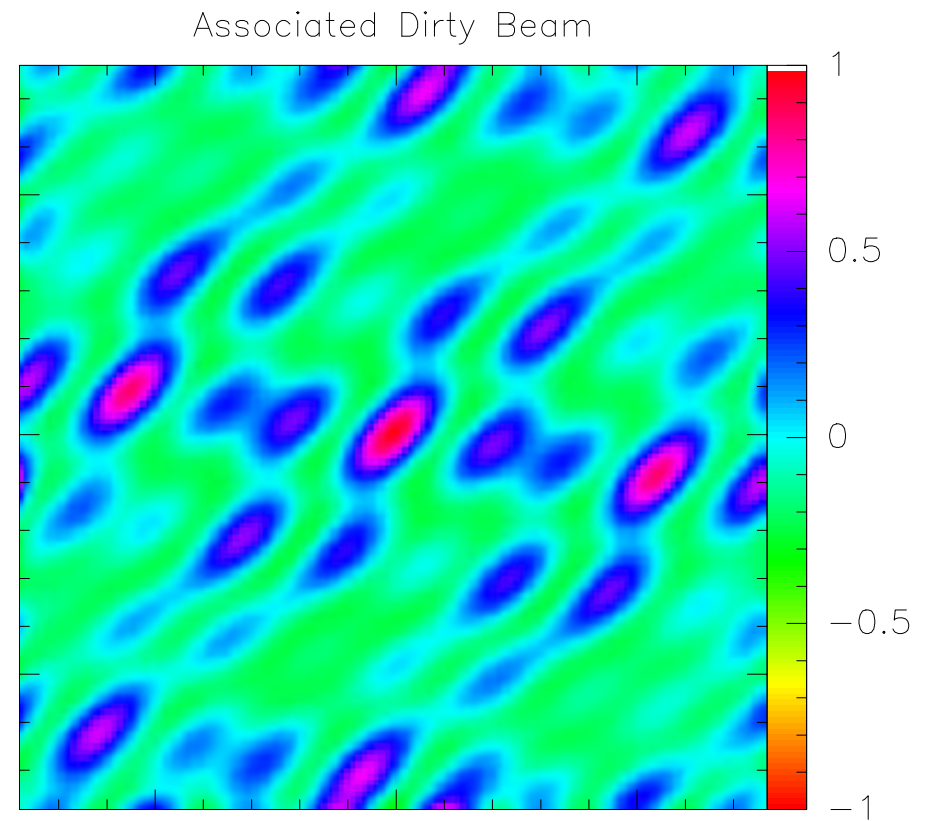
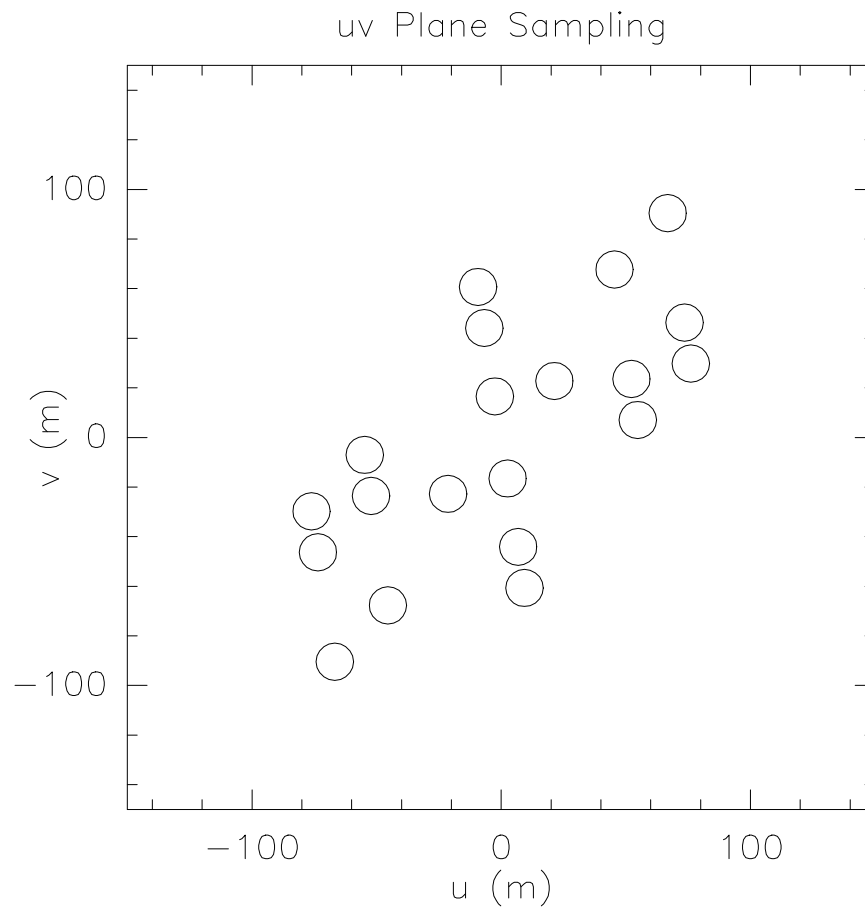
Dirty Beam Shape and Number of Antenna:

4 Antenna



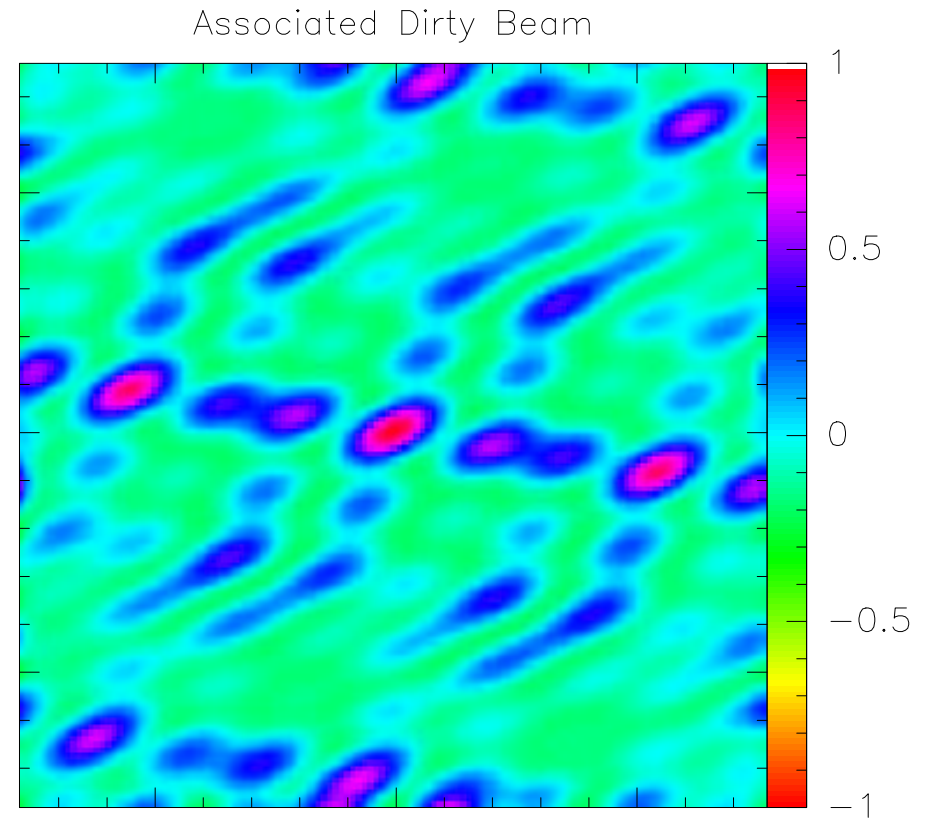
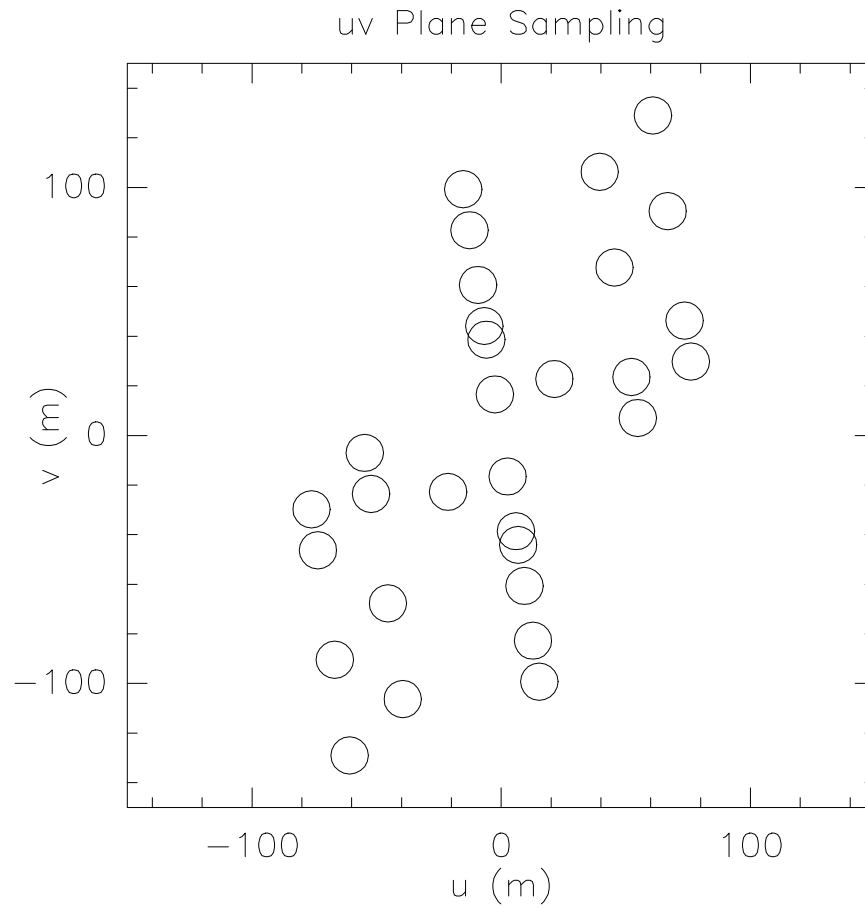
Dirty Beam Shape and Number of Antenna:

5 Antenna

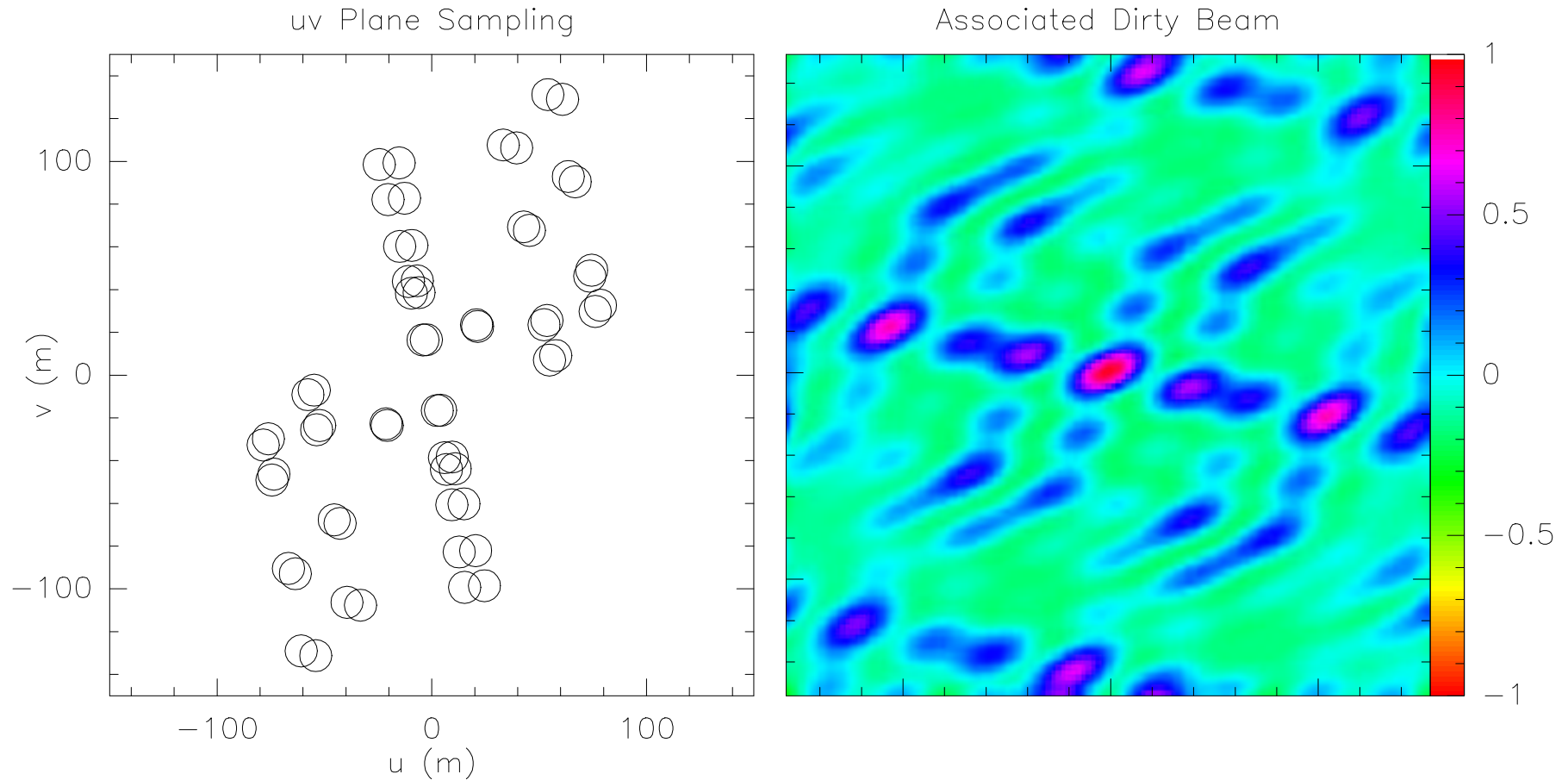


Dirty Beam Shape and Number of Antenna:

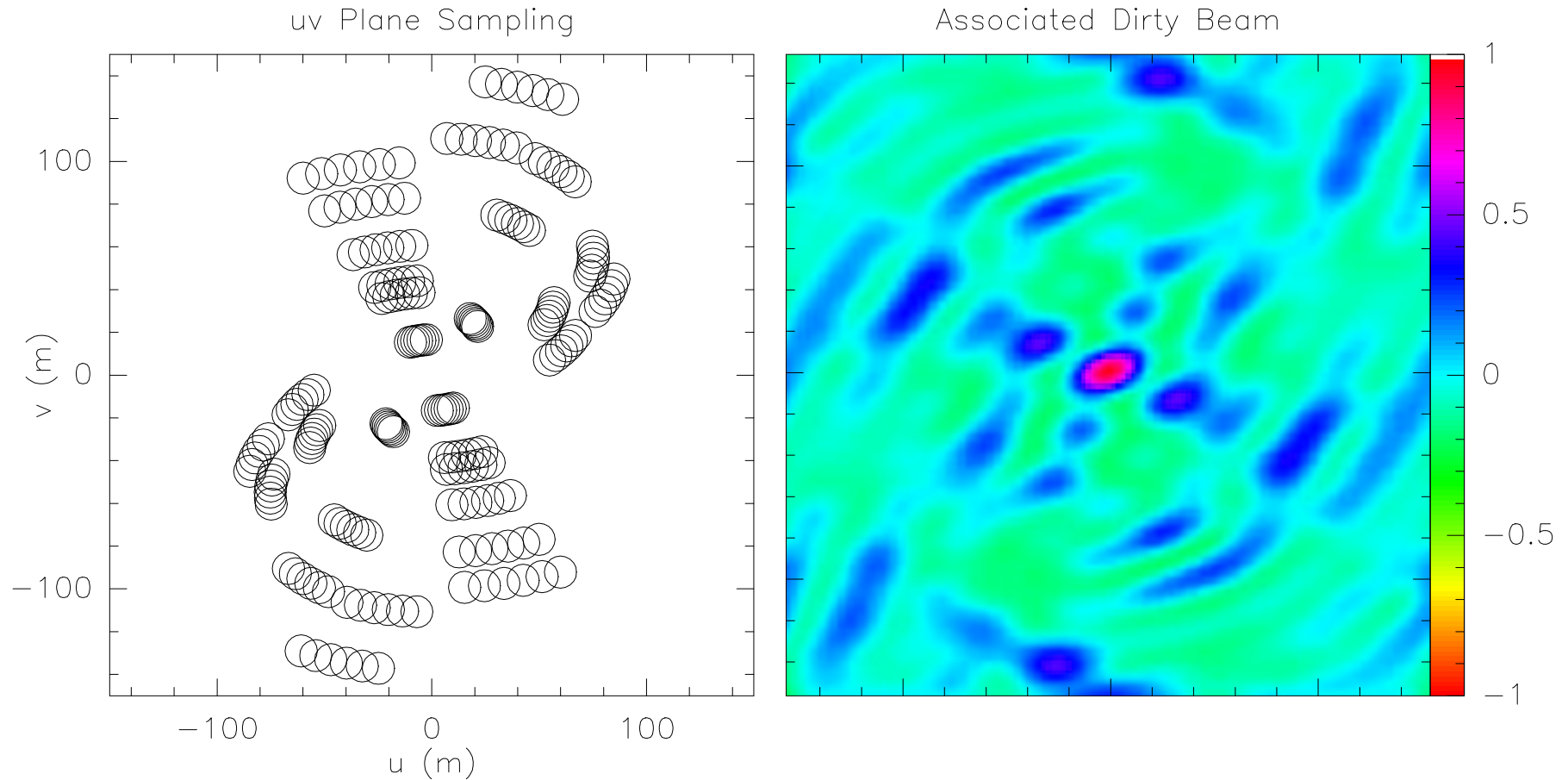
6 Antenna



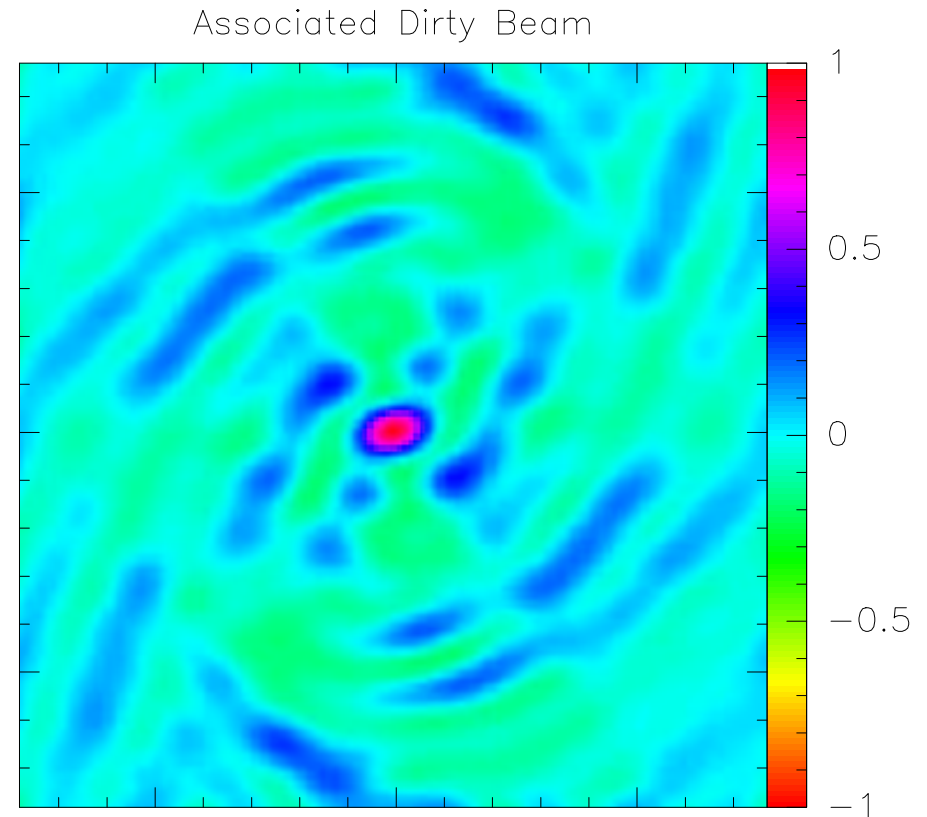
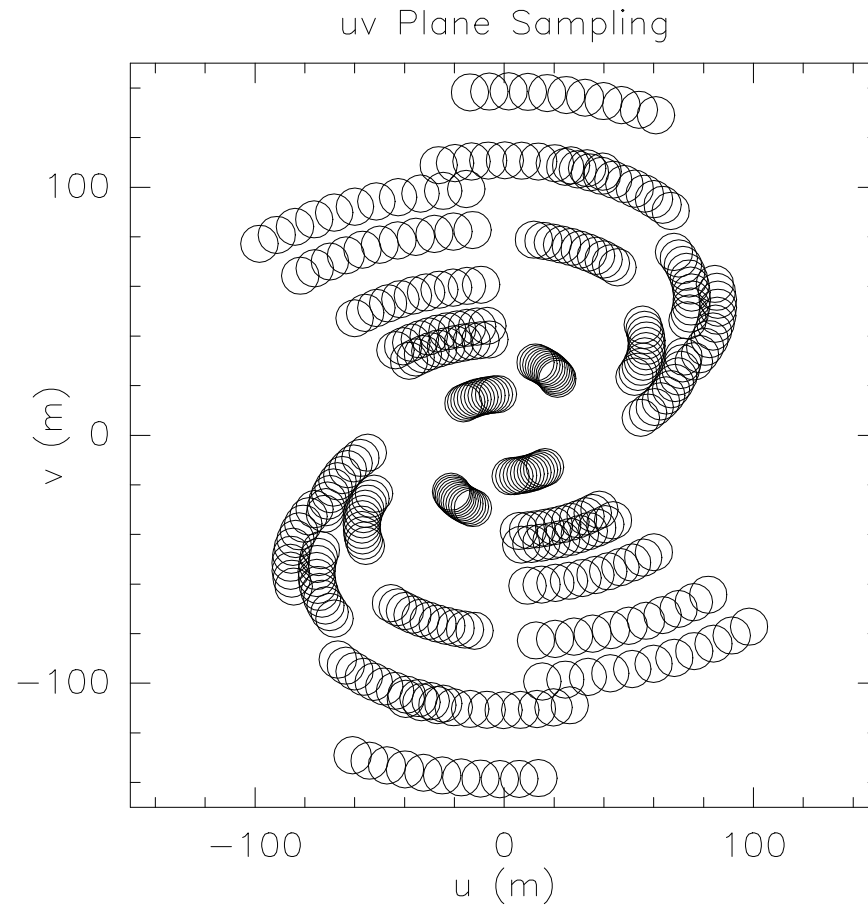
Dirty Beam Shape and Super Synthesis



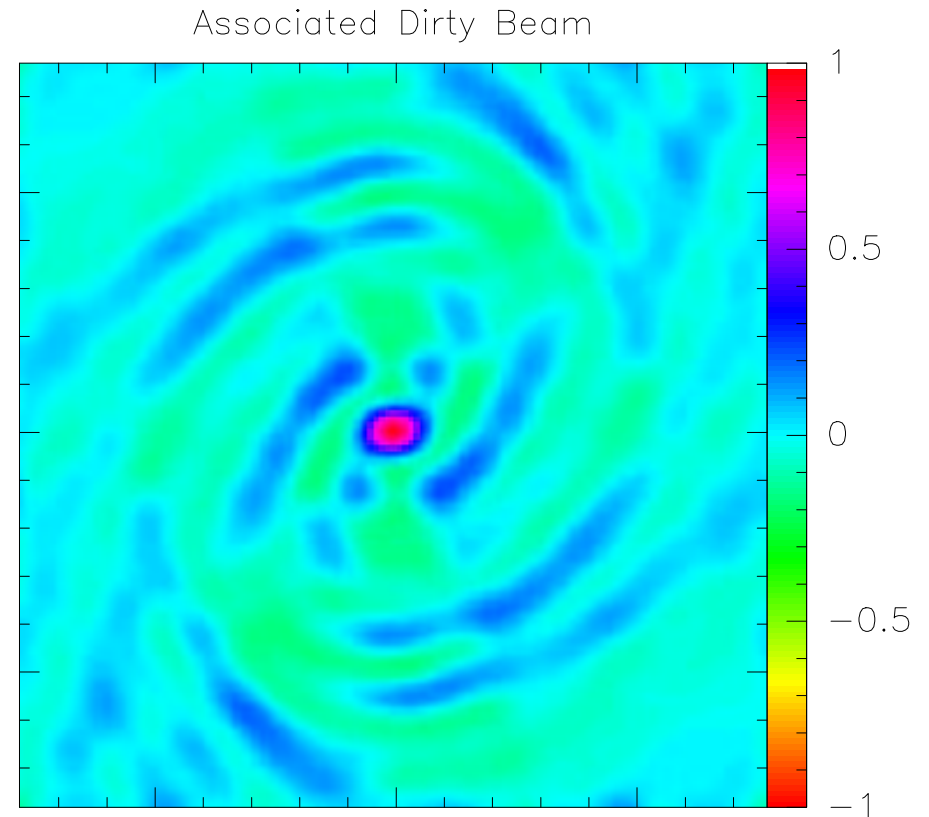
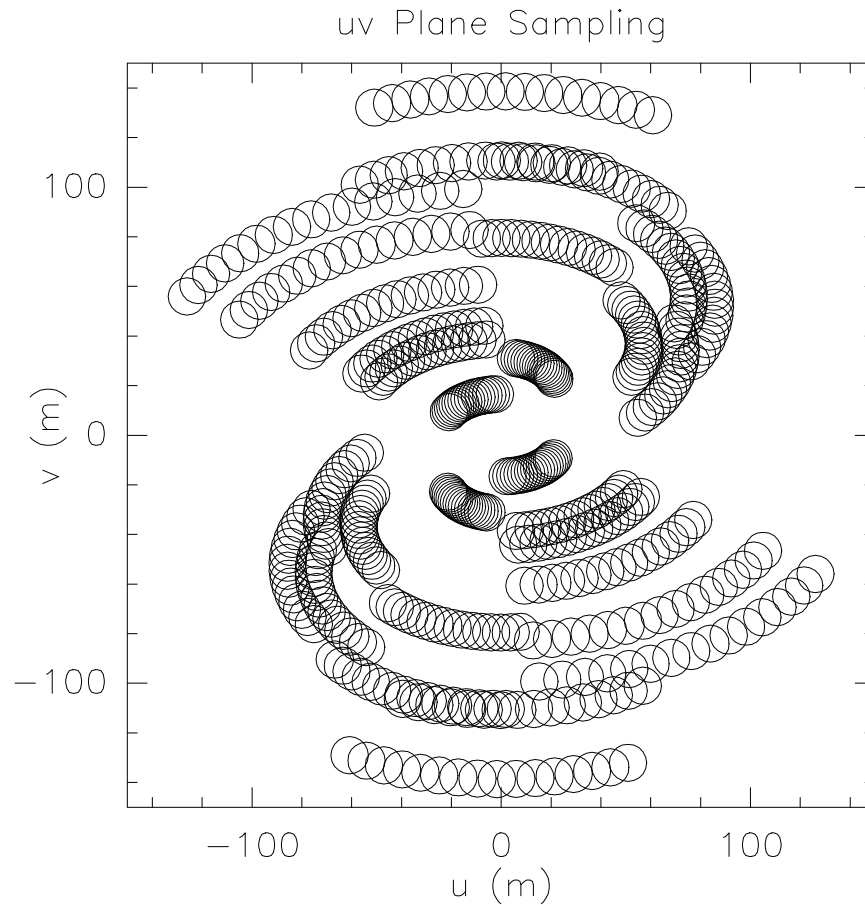
Dirty Beam Shape and Super Synthesis



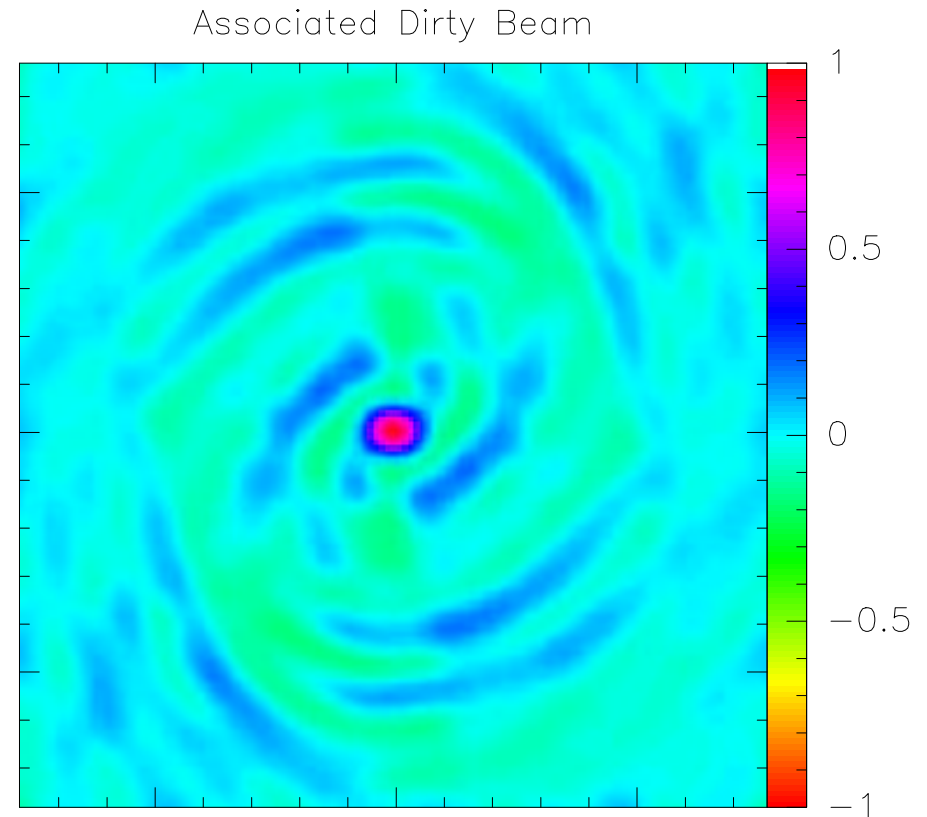
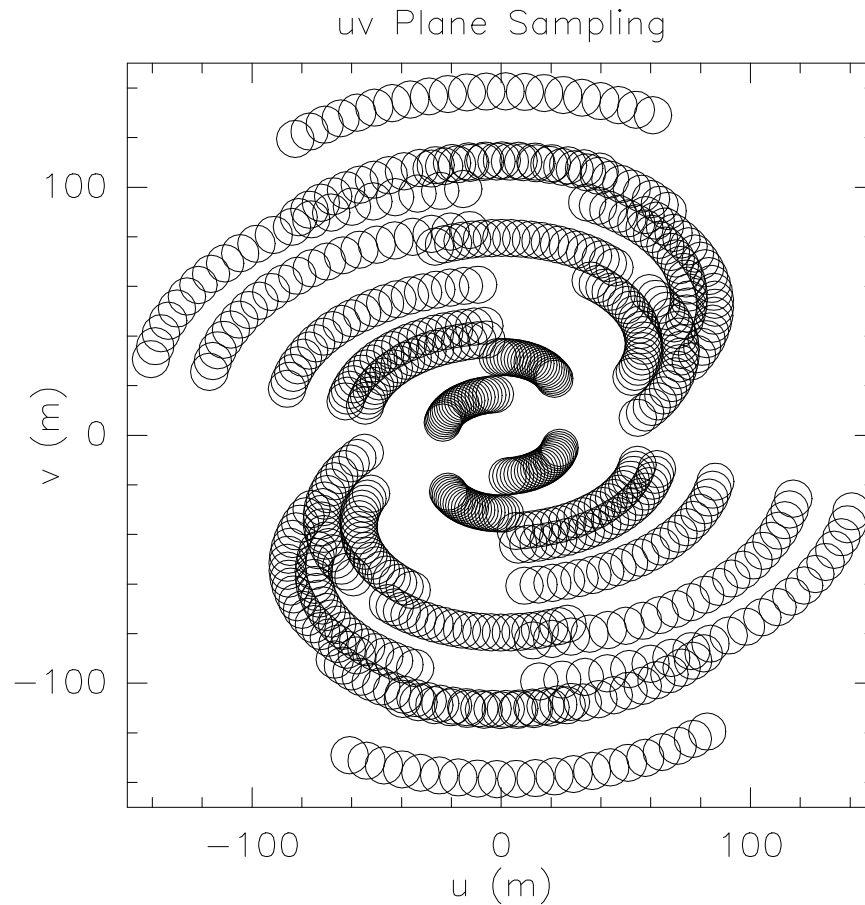
Dirty Beam Shape and Super Synthesis



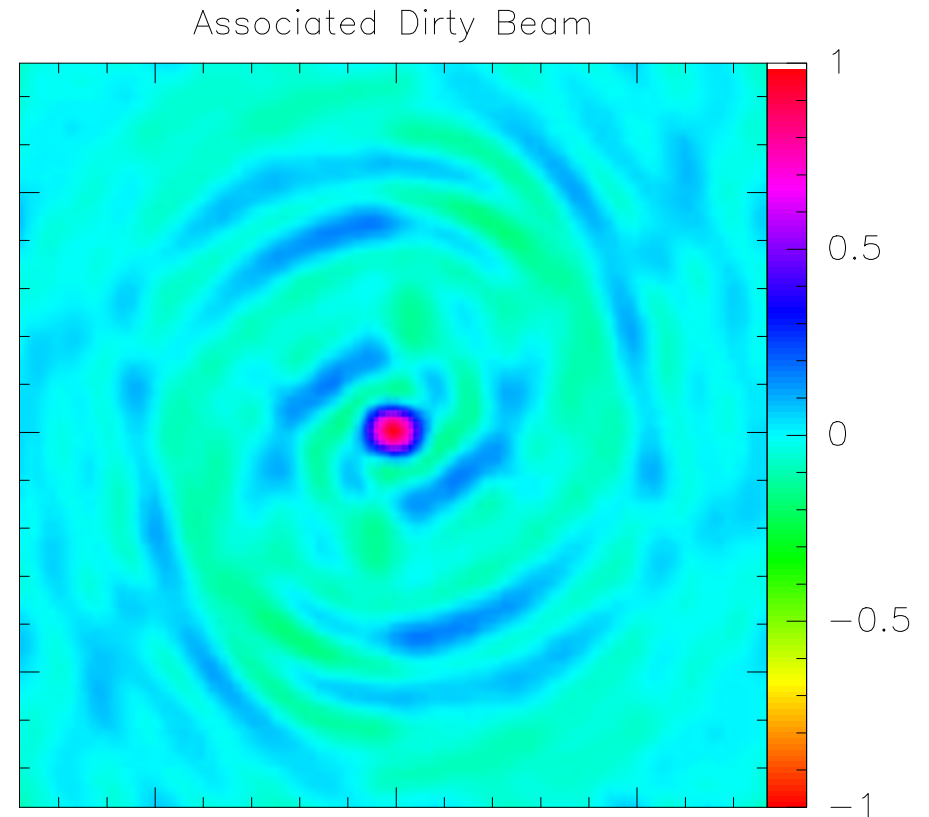
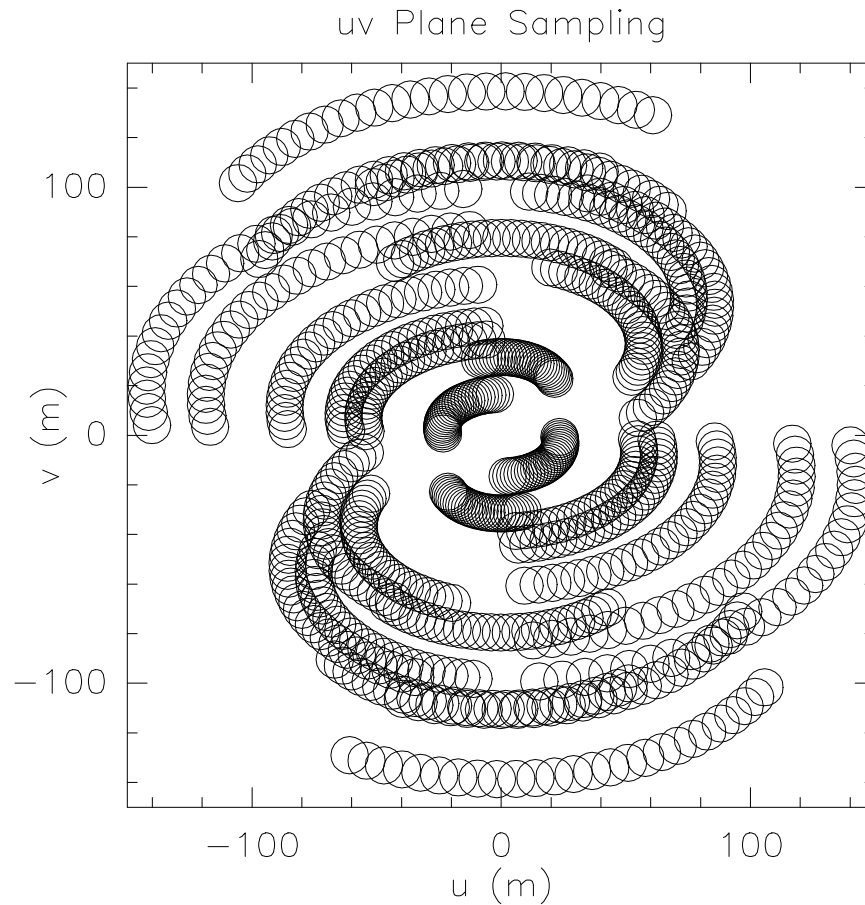
Dirty Beam Shape and Super Synthesis



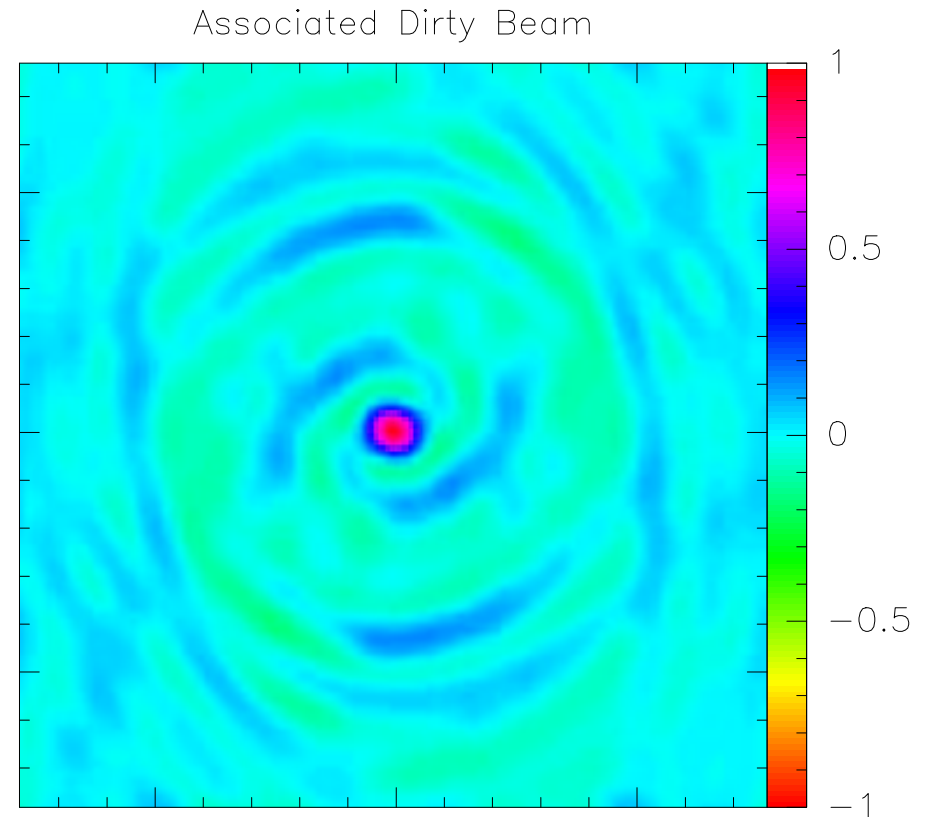
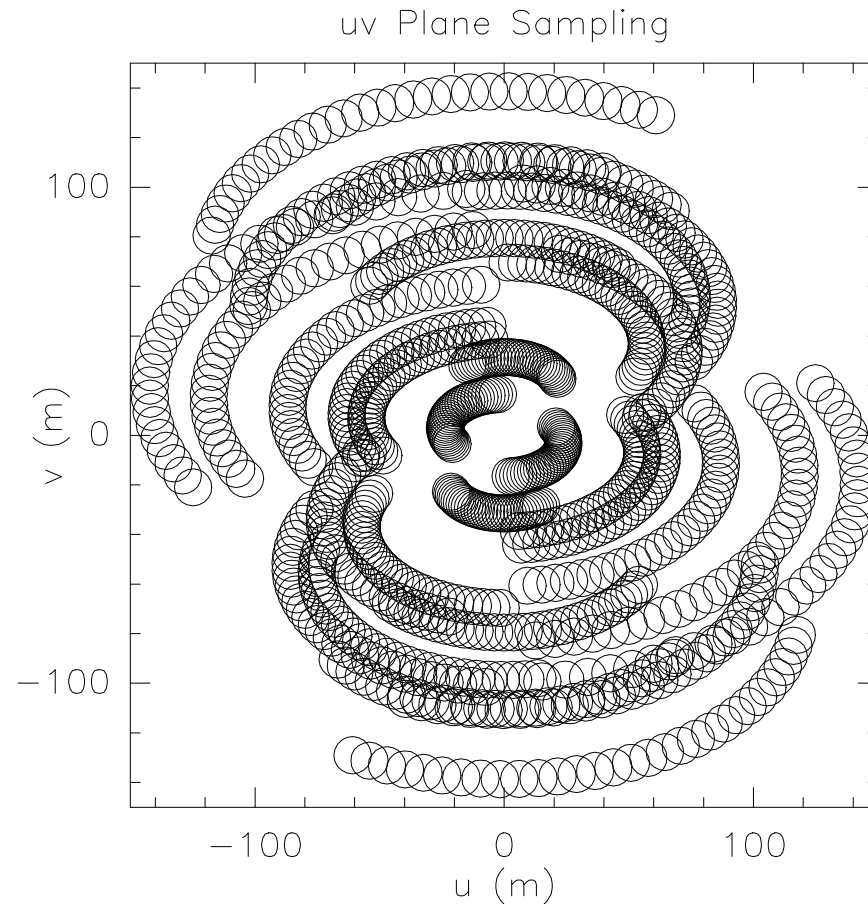
Dirty Beam Shape and Super Synthesis



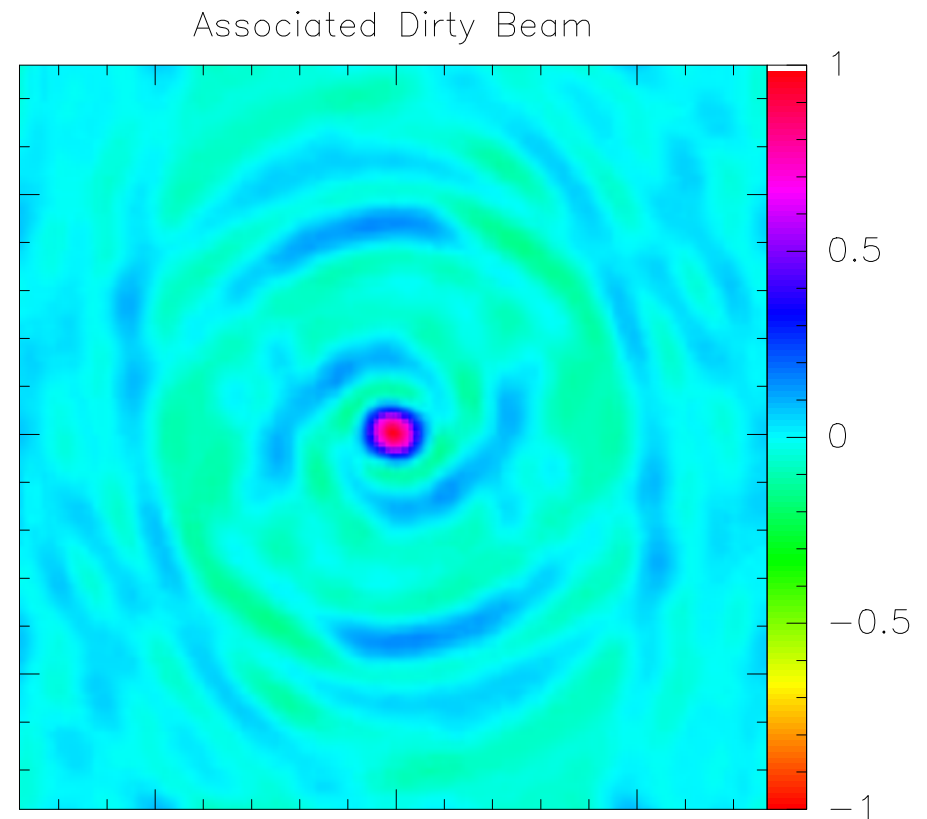
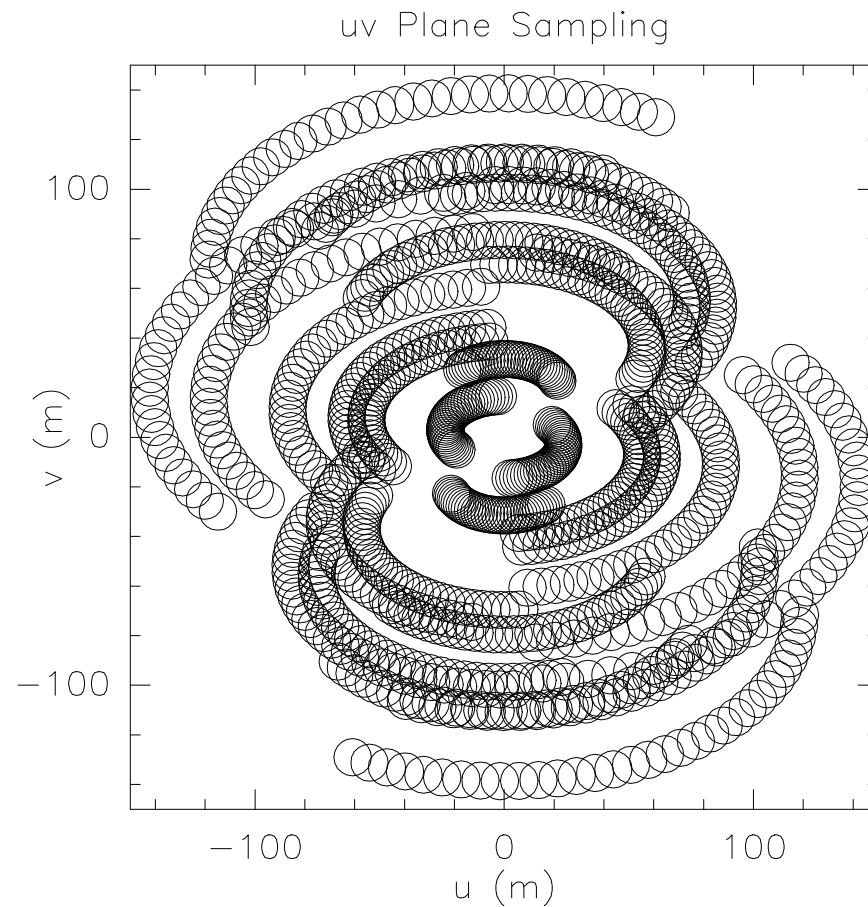
Dirty Beam Shape and Super Synthesis



Dirty Beam Shape and Super Synthesis



Dirty Beam Shape and Super Synthesis



Dirty Beam Shape and Weighting

Natural Weighting: Default definition of the irregular sampling function at uv table creation.

- $S(u, v) = 1/\sigma^2$ at (u, v) points where visibilities are measured;
- $S(u, v) = 0$ elsewhere;

with $\sigma^2(u, v)$ the noise variance of the visibility.

Introduction of a weighting function $W(u, v)$:

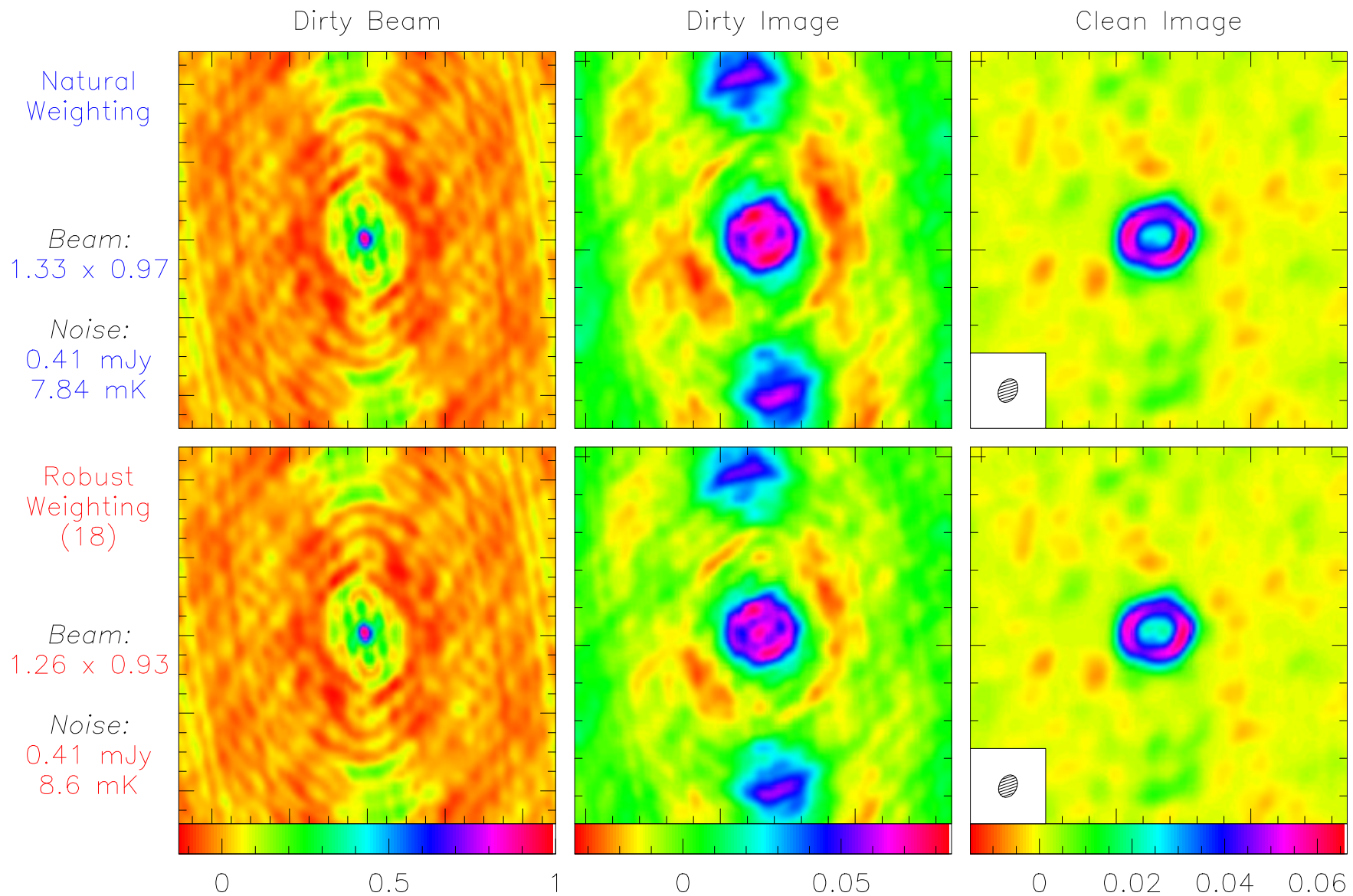
- $B_{\text{dirty}} = 2\text{D FT}^{-1} \{W.S\}$;
- **Robust weighting:** W enhance the **large** baseline contribution;
- **Tapering:** W enhance the **small** baseline contribution.

Robust Weighting: I. Definition

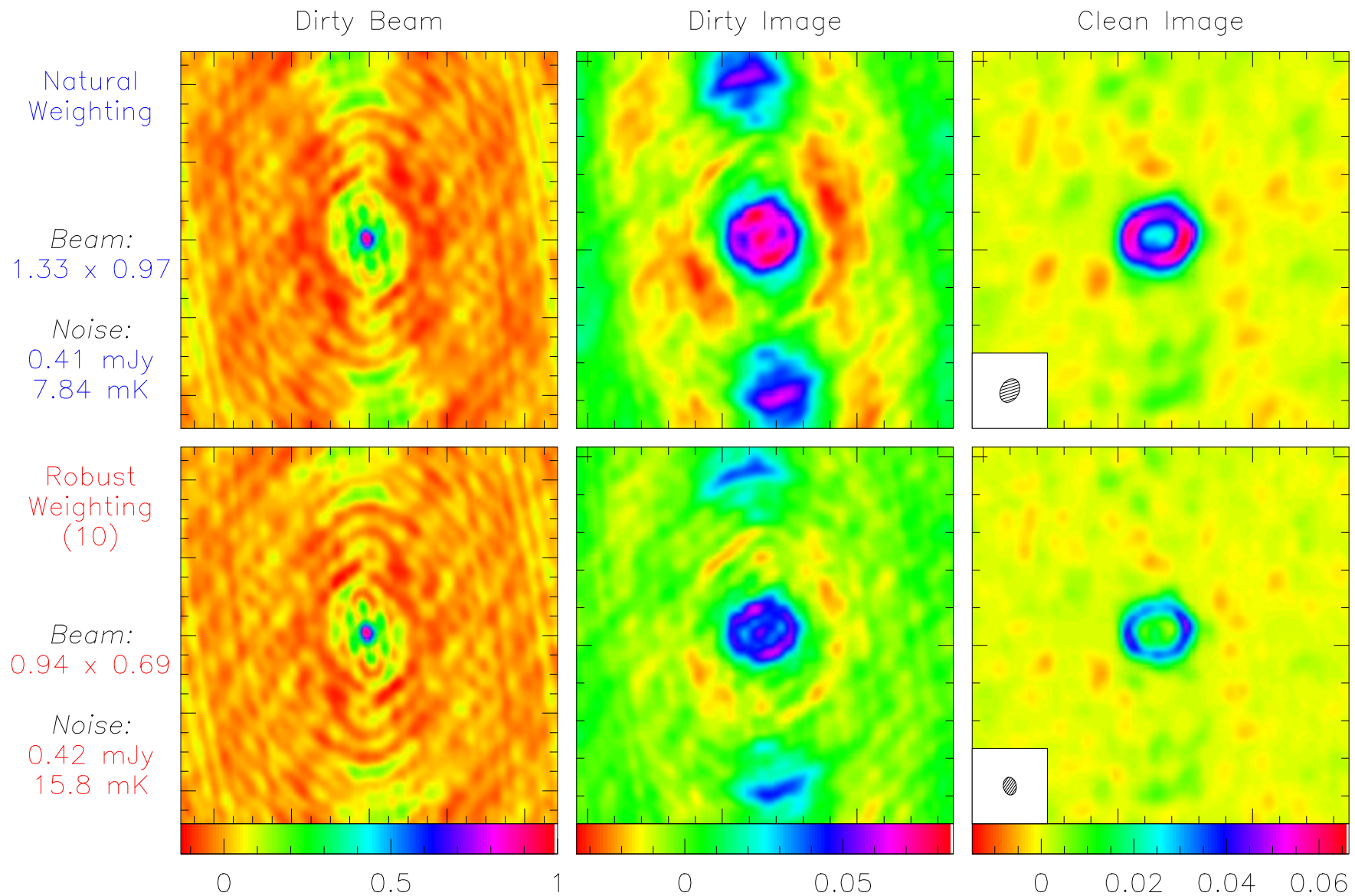
Definitions:

- $\text{Natural} = \sum_{(u,v) \in \text{Cell}} S;$
- $\sum_{(u,v) \in \text{Cell}} W.S = \begin{cases} \text{Constant} & \text{if } (\text{Natural} \geq \text{Threshold}); \\ \text{Natural} & \text{else;} \end{cases}$
- In practice, the cell size is $0.5D$.

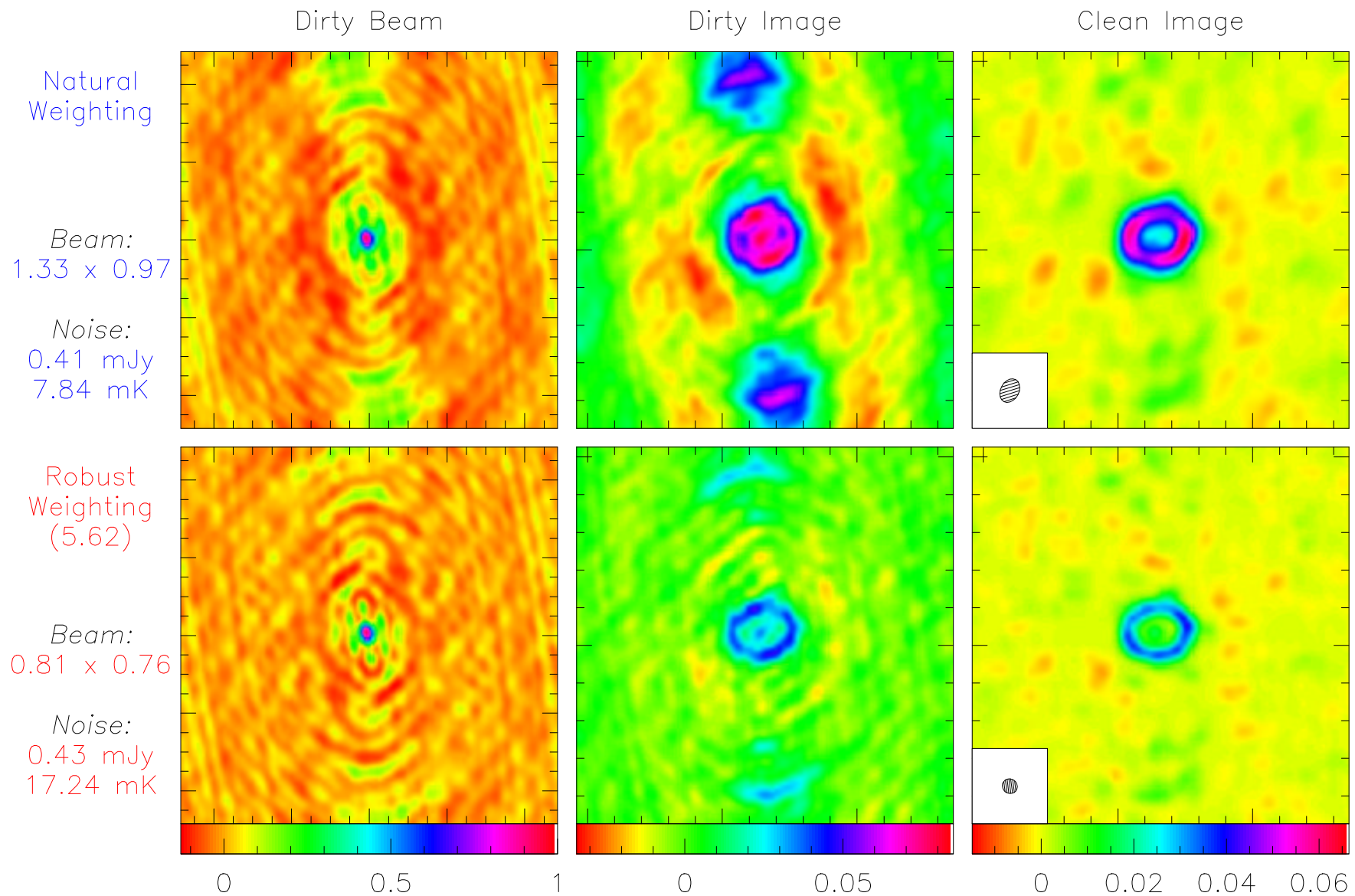
Robust Weighting: II. Examples



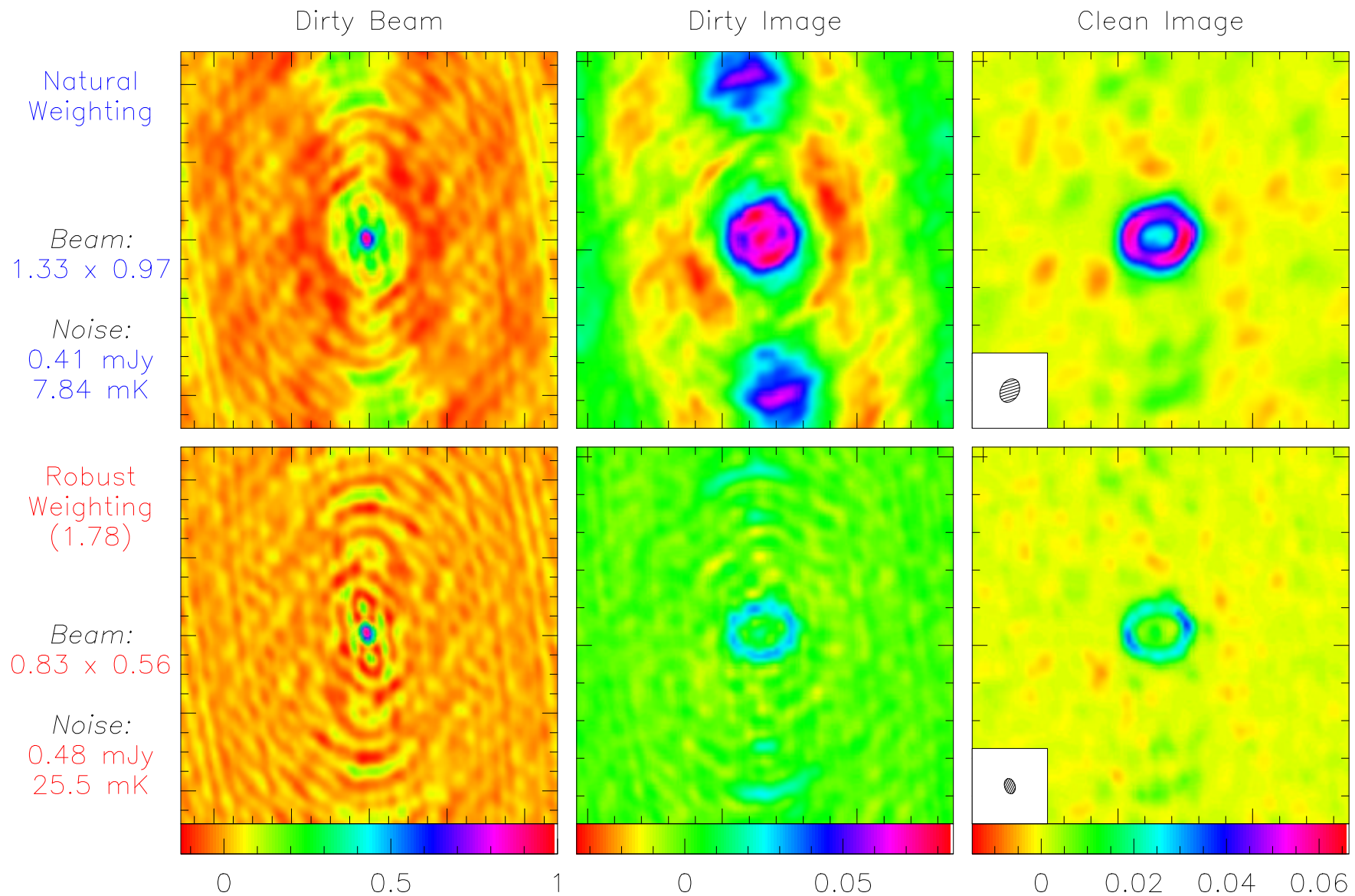
Robust Weighting: II. Examples



Robust Weighting: II. Examples



Robust Weighting: II. Examples



Robust Weighting: III. Definition and Properties

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- $\text{Natural} = \sum_{(u,v) \in \text{Cell}} S;$
- $\sum_{(u,v) \in \text{Cell}} W.S = \begin{cases} \text{Constant} & \text{if } (\text{Natural} \leq \text{Threshold}); \\ \text{Natural} & \text{else;} \end{cases}$
- In practice, the cell size is $0.5D$.

Properties:

- Increase the resolution;
- Lower the sidelobes;
- Degrade point source sensitivity.

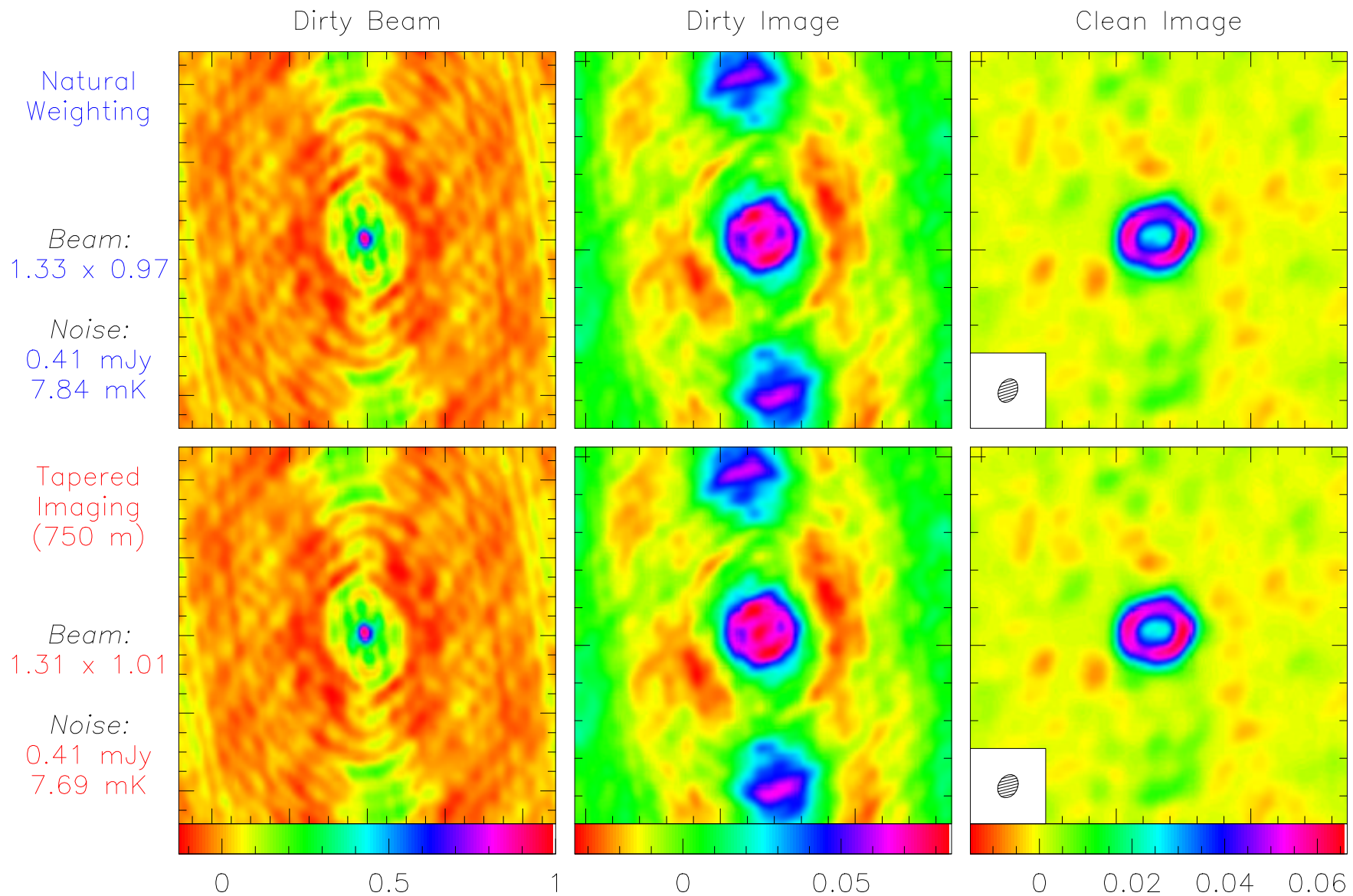
Unfortunately: GILDAS implementation gives it the name of “uniform” weighting!

Tapering: I Definition

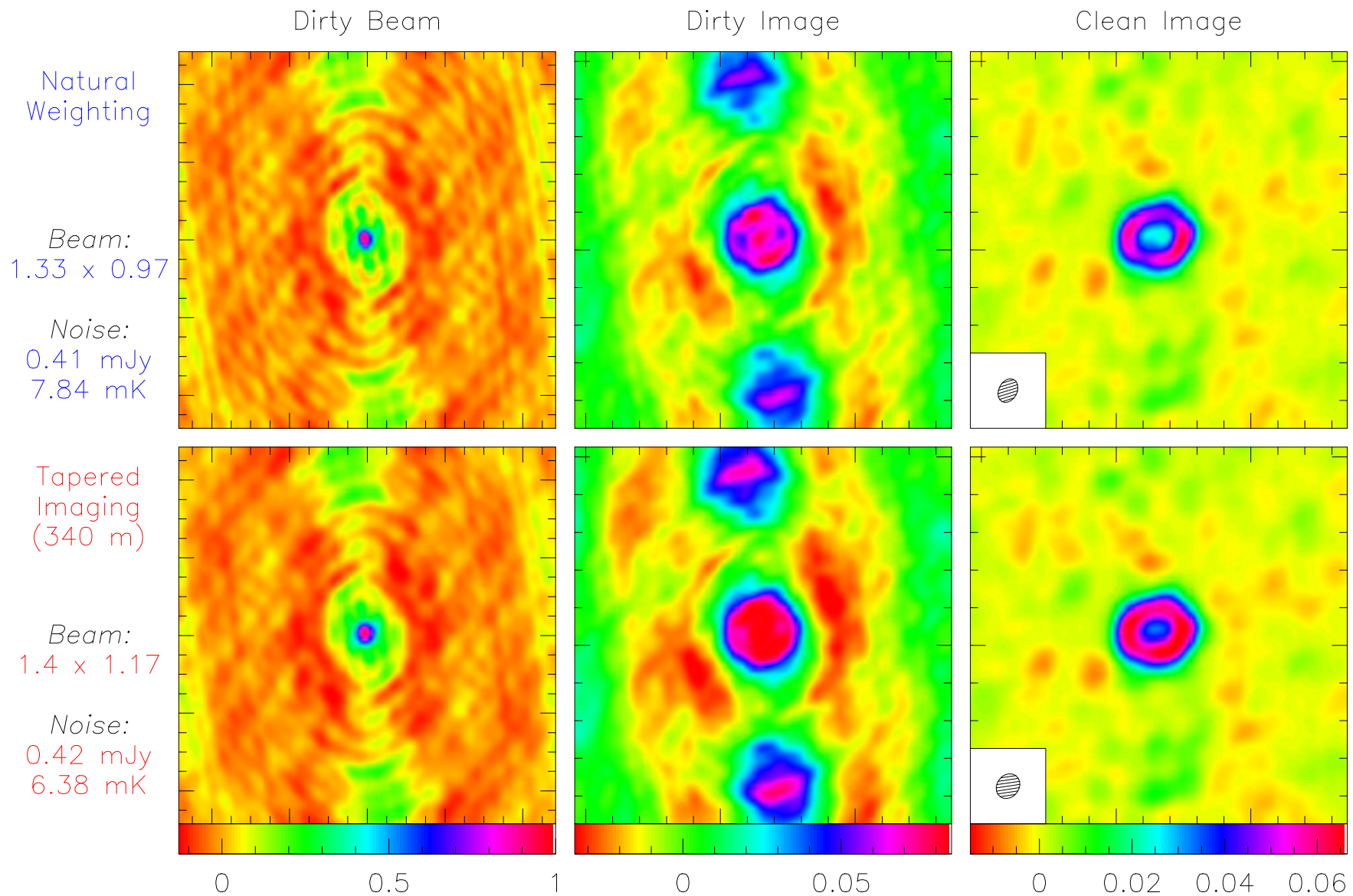
Definition:

- Apodization of the uv coverage in general by a Gaussian;
 - $W = \exp \left\{ -\frac{(u^2 + v^2)}{t^2} \right\}$ where t = tapering distance.
- ⇒ Convolution (*i.e.* smoothing) of the image by a Gaussian.

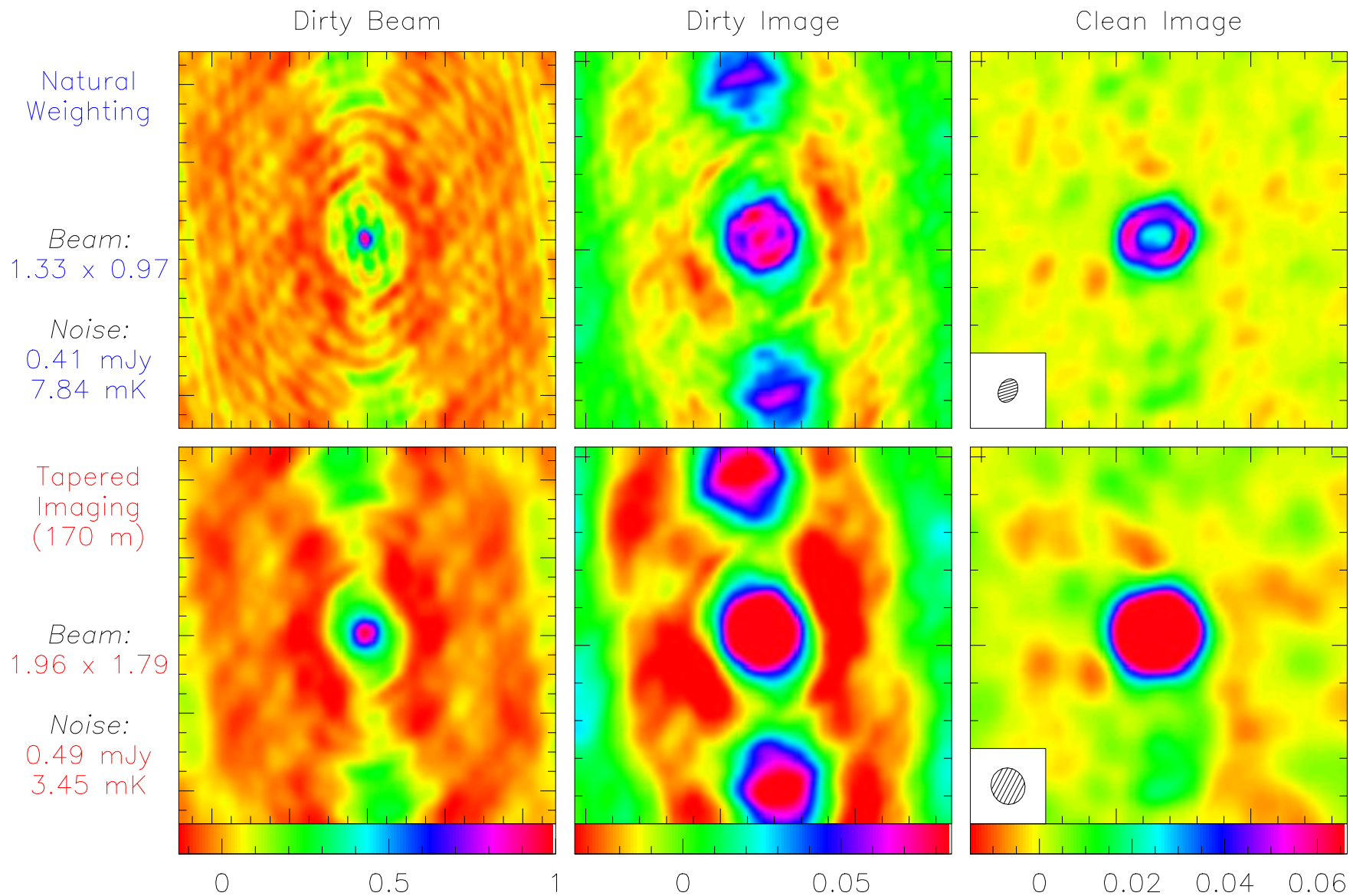
Tapering: II. Examples



Tapering: II. Examples



Tapering: II. Examples



Tapering: III. Definition and Properties

Definition:

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- ⇒ Convolution (*i.e.* smoothing) of the image by a Gaussian.

Properties:

- Decrease the resolution;
- Degrade point source sensitivity;
- Increase sensitivity to “medium size” structures.

Inconvenient: Throw out some information.

⇒ To increase sensitivity to extended sources, use compact arrays not tapering.

Weighting and Tapering: Summary

	Robust	Natural	Tapering
Resolution	High	Medium	Low
Side Lobes	↘	Medium	?
Point Source Sensitivity	↘	Maximum	↘
Extended Source Sensitivity	↘	Medium	↗

Non-circular tapering + Robust weighting:
Sometimes \Rightarrow Better (*i.e.* smaller and more circular) beams.

Weighting and Tapering: GILDAS implementation

Resolution, point/extended source sensitivity
as a function of
robust threshold or tapering distance.

MAPPING> UV_STAT WEIGHT

Robust	Major (")	Minor (")	PA (deg)	Noise (mJy)	(K)	Sidelobe %	
0.10	0.840	0.527	18.5	0.791	0.044	-16.1	13.9
None	1.271	0.940	155.1	0.406	0.008	-2.7	25.9

I-UV_STAT, Recommended pixel size is 0.080 - 0.264"

MAPPING> UV_STAT TAPER

Taper (m)	Major (")	Minor (")	PA (deg)	Noise (mJy)	(K)	Sidelobe %	
30.00	4.844	3.817	11.9	1.019	0.001	-44.7	14.5
None	1.323	0.967	151.5	0.406	0.008	-12.9	28.7

From Calibrated Visibilities to Images: GILDAS implementation

MAPPING> INPUT UV_MAP: display UV_MAP control parameters.

Default = 0 \Rightarrow Try something clever.

- Gridding kernel: **CONVOLUTION** (default: 5, *i.e.* spheroidals).
- Data cube setup:
 - First and last data channels to map: **MCOL** (default: 0, *i.e.* all channels).
 - Pixel size: **MAP_CELL** (in arcsec, default: 0, *i.e.* 1/3 to 1/4 synthesized beam).
 - Map size: **MAP_SIZE** (in pixels, default: 0, *i.e.* \sim twice primary beam size).
- Weighting:
 - kind: **WEIGHT_MODE**
(Possibilities: NATURAL/UN. Default: NATURAL).
 - Size of uv plane cell and robust threshold: **UV_CELL**
(Defaults: 7.5 m, 1).
- Tapering: Gaussian taper parameters **UV_TAPER** (in m and degree, default: 0, *i.e.* no tapering).

From Calibrated Visibilities to Images: Summary

Fourier Transform and Deconvolution:
The two key issues in imaging.

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Calibrated Visibilities	
↓ Fourier Transform	UV_STAT, UV_MAP
Dirty beam & image	
↓ Deconvolution	HOGBOM, CLARK
Clean beam & image	
↓ Visualization	GO_BIT, GO_VIEW
↓ Image analysis	GO_NOISE, GO_FLUX, GO_MOMENTS
Physical information on your source	

Deconvolution: I. Philosophy

$$I_{\text{meas}} = B_{\text{dirty}} * \{B_{\text{primary}} \cdot I_{\text{source}}\} + N.$$

Information lost:

- Irregular, incomplete sampling \Rightarrow convolution by B_{dirty} ;
- Noise \Rightarrow Low signal structures undetected.

\Rightarrow 1. Impossible to recover the intrinsic source structure!

\Rightarrow 2. Infinite number of solutions!

$$\left\{ \begin{array}{l} S \text{ solution (i.e. } I_{\text{meas}} = B_{\text{dirty}} * S + N) \\ B_{\text{dirty}} * R = 0 \end{array} \right\} \Rightarrow (S + R) \text{ solution.}$$

Deconvolution: I. Philosophy (continued)

$$I_{\text{meas}} = B_{\text{dirty}} * \{B_{\text{primary}} \cdot I_{\text{source}}\} + N.$$

Information lost:

- ⇒ 1. Impossible to recover the intrinsic source structure!
- ⇒ 2. Infinite number of solutions!

Deconvolution goal: Finding a **sensible** intensity distribution **compatible** with the intrinsic source one.

Deconvolution needs:

- Some *a priori* assumptions about the source intensity distribution;
- As much as possible knowledge of
 - B_{dirty} (OK in radioastronomy);
 - Noise properties.

The best solution: A Gaussian $B_{\text{dirty}} \Rightarrow$ No deconvolution needed!

Deconvolution: II. MEM principle

a priori assumptions: Smoothed and positive intensity.

Idea:

“Select from the images that agree with the measured visibilities to within the noise level the one that maximizes entropy.”

Algorithm:

- Entropy:

$$\mathcal{S} = - \sum_{ij} I_{ij} \log(I_{ij}/M_{ij}) \text{ with } M = \text{first guess image.}$$

- Constraint:

$$\sum_k \frac{|V(u_k, v_k) - \tilde{I}(u_k, v_k)|^2}{\sigma_k^2} = \text{number of visibilities}$$

with $\tilde{I} = 2D \text{ FT}(I)$.

Deconvolution: II. MEM properties

Advantages:

- Fast:
Computational load $\propto N \ln(N)$ with $N =$ number of pixels.
- Easy to generalize (Arrays with different antenna diameters).
- Flatten low-level extended emission.
- Resolve peaks.

Inconvenients:

- Angular resolution increases with peak height.
- Unable to clean ripples (e.g. point source sidelobes) in extended emission.
- Biased residuals:
 \Rightarrow Noise increase and spurious emission at low signal.
- Impossibility to deal with absorption features.
- Poor performance with limited uv coverage
 \Rightarrow **Not** used at PdBI.

Deconvolution: III. The Basic CLEAN Algorithm

a priori assumption: Source = Collection of point sources.

Idea: “Matching pursuit”.

Algorithm:

1 Initialize

- the residual map to the dirty map;
- the Clean component list to an empty (NULL) value;

2 Identify pixel of $|I_{\max}|$ in residual map as a point source;

3 Add $\gamma \cdot I_{\max}$ to clean component list;

4 Subtract $\gamma \cdot I_{\max}$ from residual map;

5 Go back to point 2 while stopping criterion is not matched;

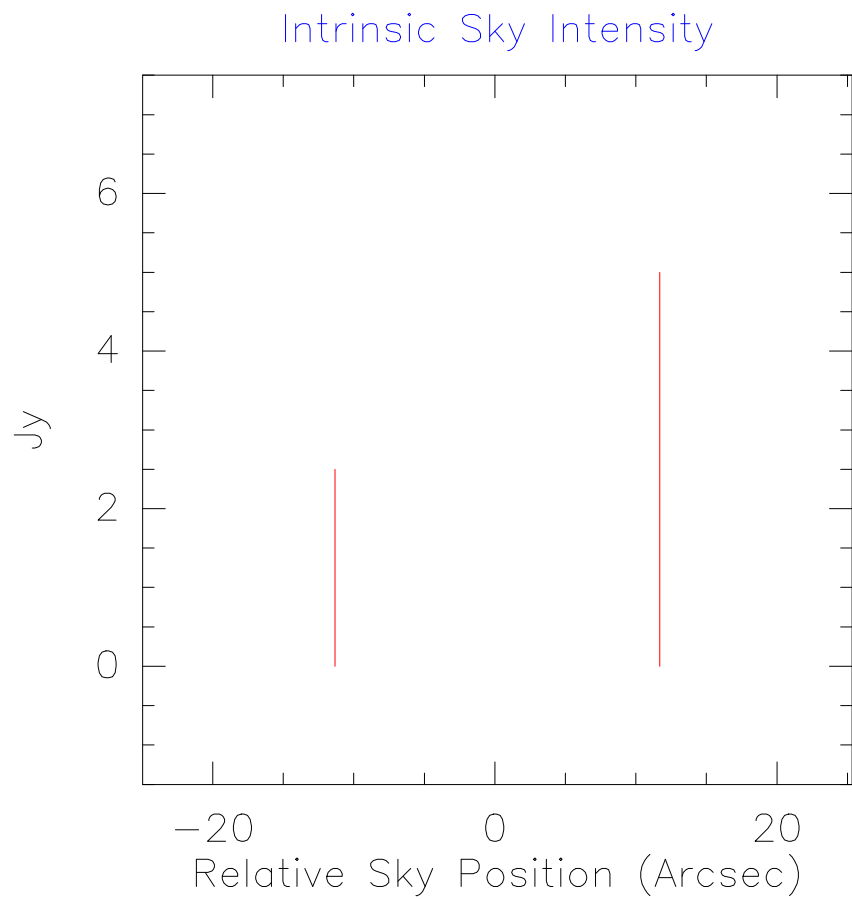
6 Convolution by Clean beam (*a posteriori* regularization);

5 Addition of residual map to enable:

- Correction when cleaning is too superficial;
- Noise estimation.

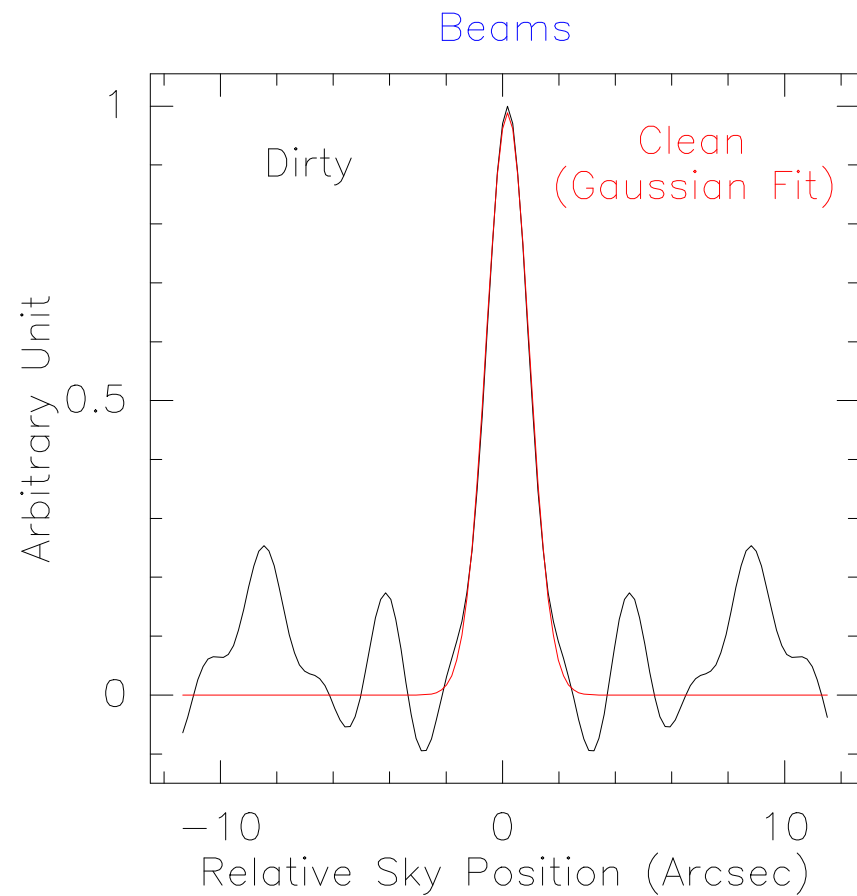
Deconvolution: III. The Basic Clean Algorithm

1. First Illustration



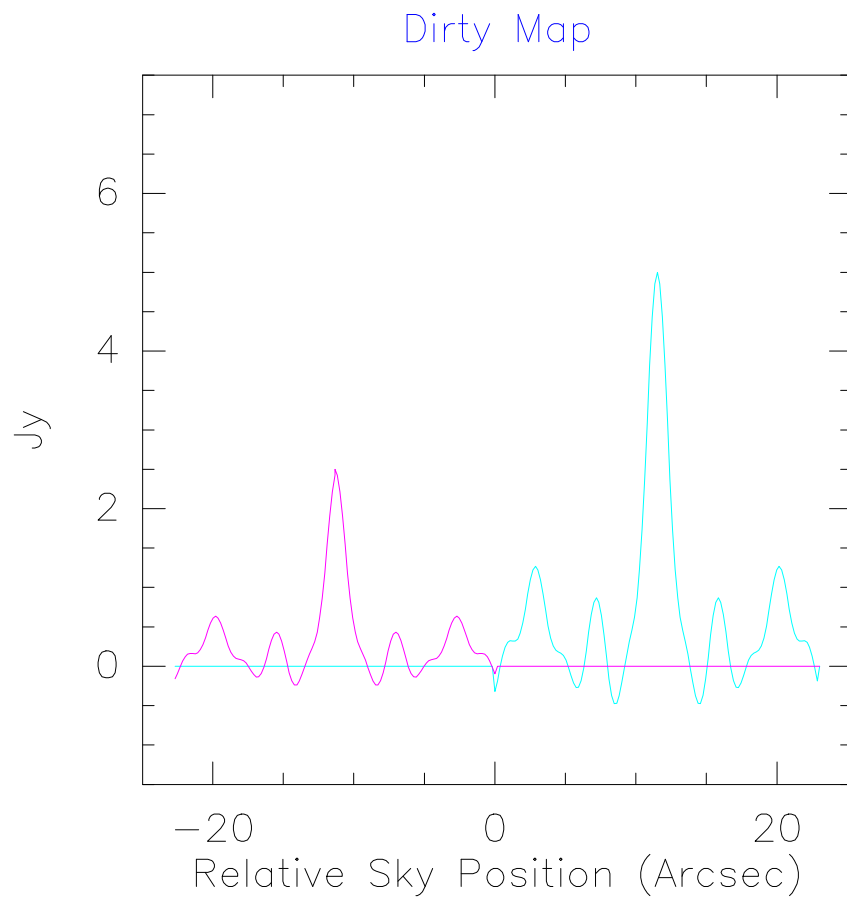
Deconvolution: III. The Basic Clean Algorithm

1. First Illustration



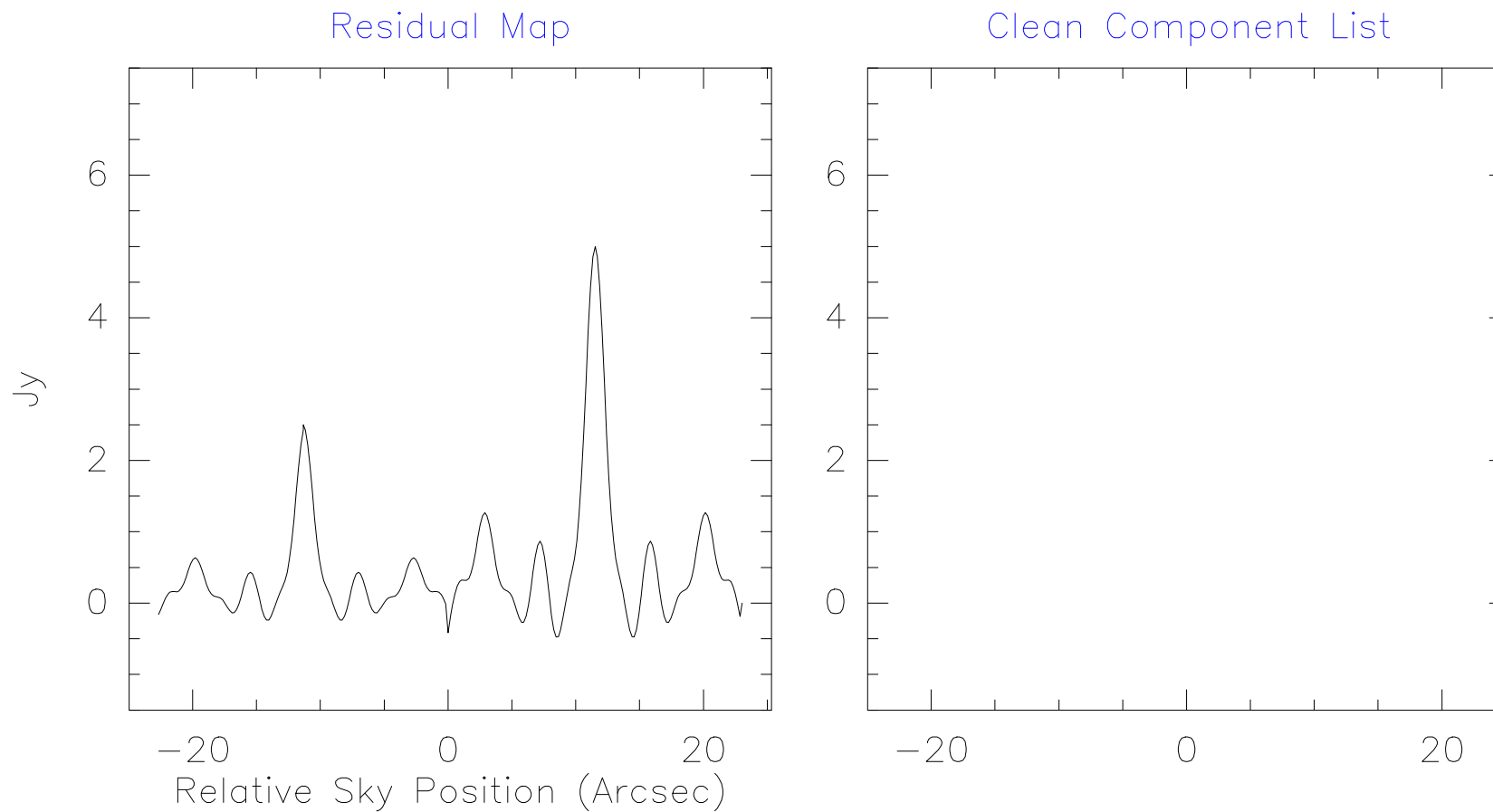
Deconvolution: III. The Basic Clean Algorithm

1. First Illustration



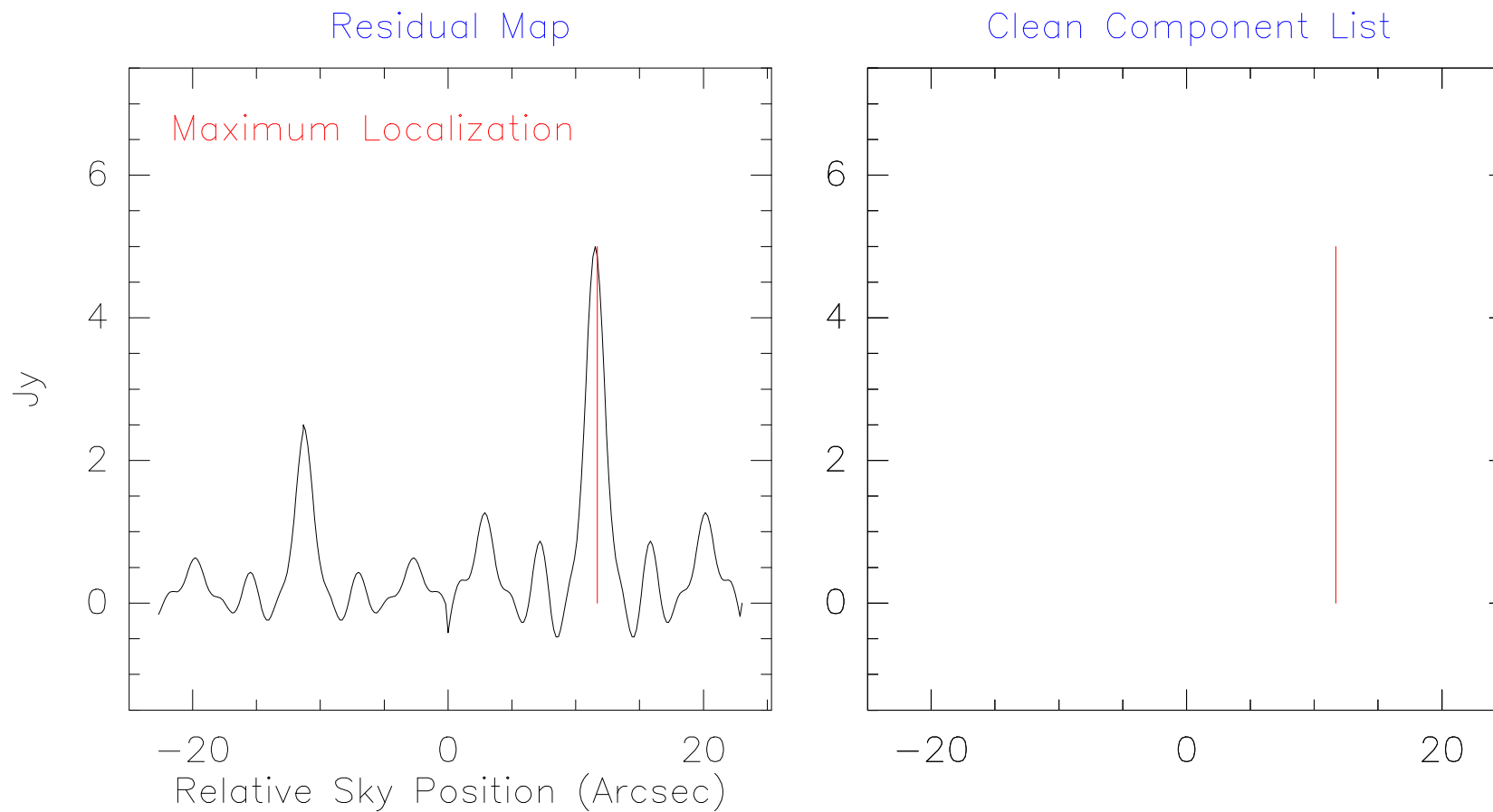
Deconvolution: III. The Basic Clean Algorithm

1. First Illustration



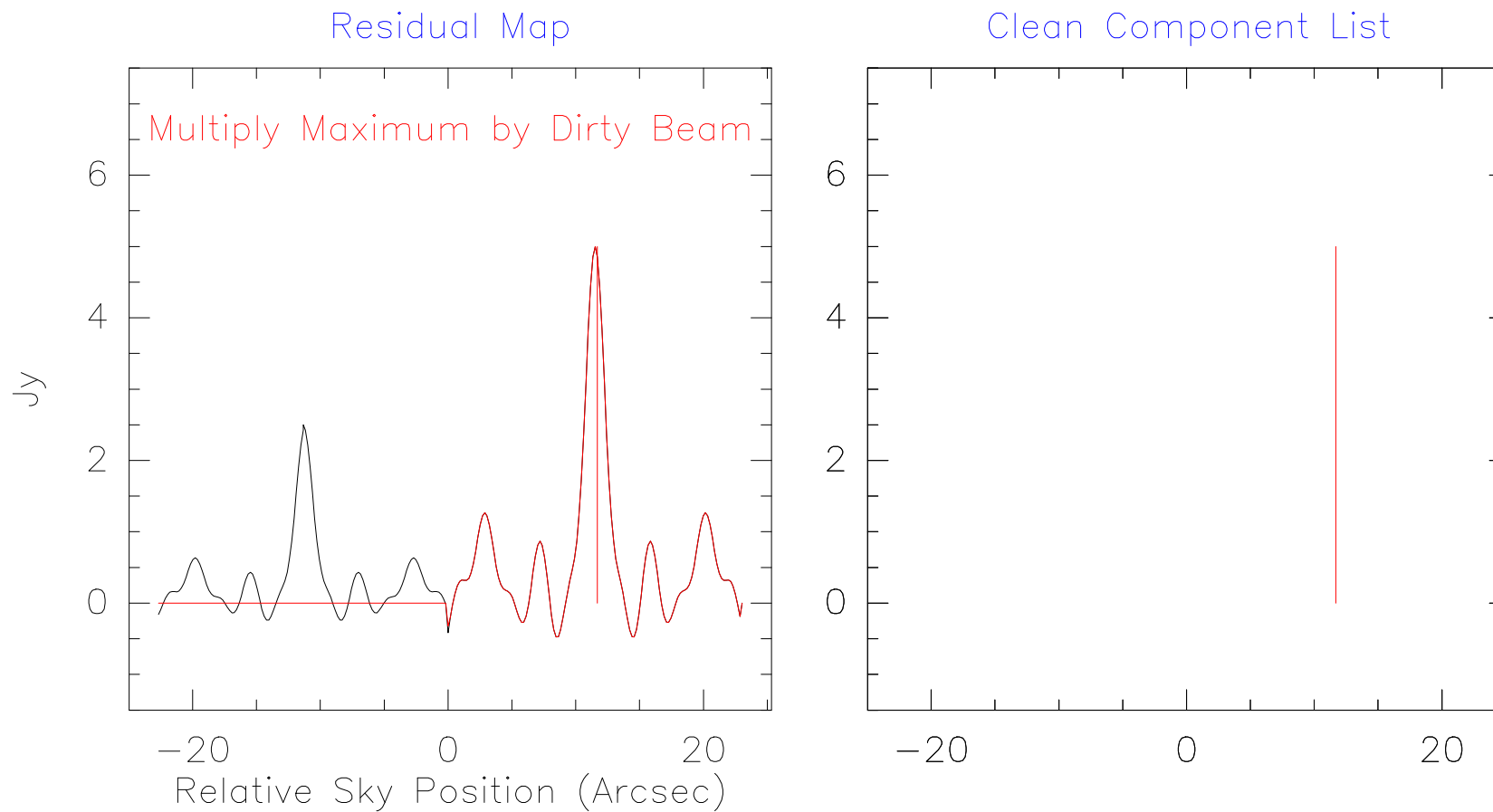
Deconvolution: III. The Basic Clean Algorithm

1. First Illustration



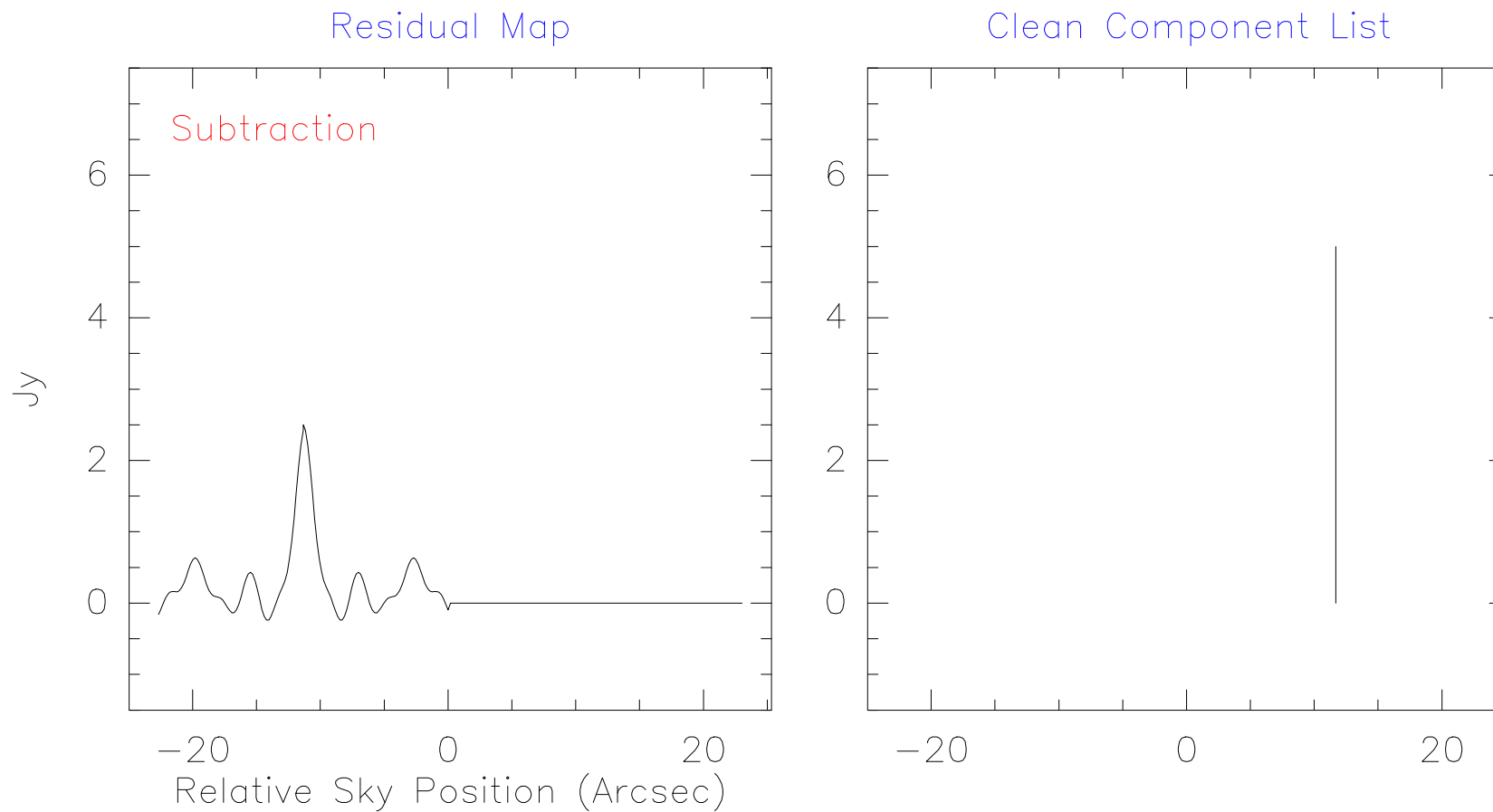
Deconvolution: III. The Basic Clean Algorithm

1. First Illustration



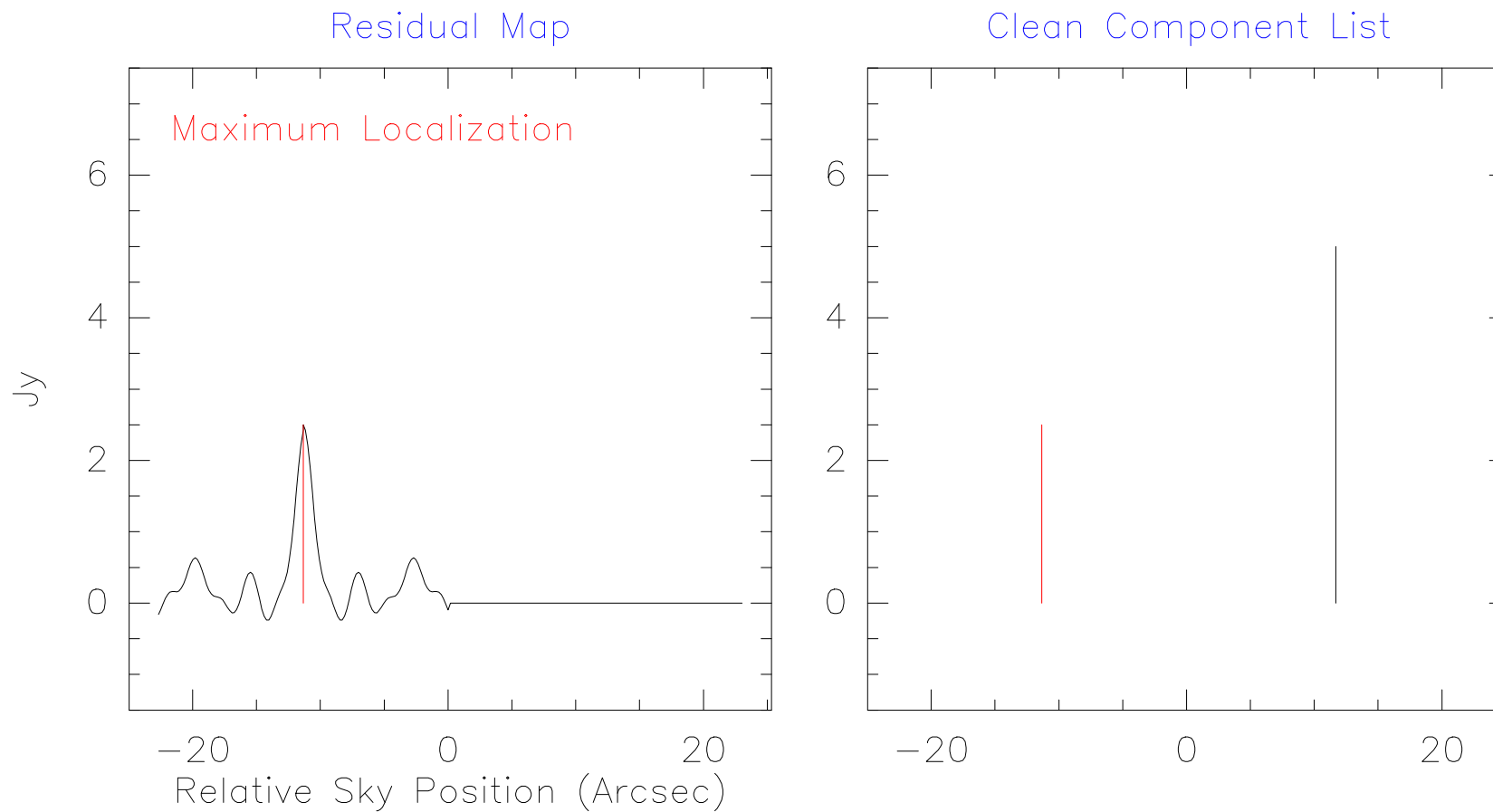
Deconvolution: III. The Basic Clean Algorithm

1. First Illustration



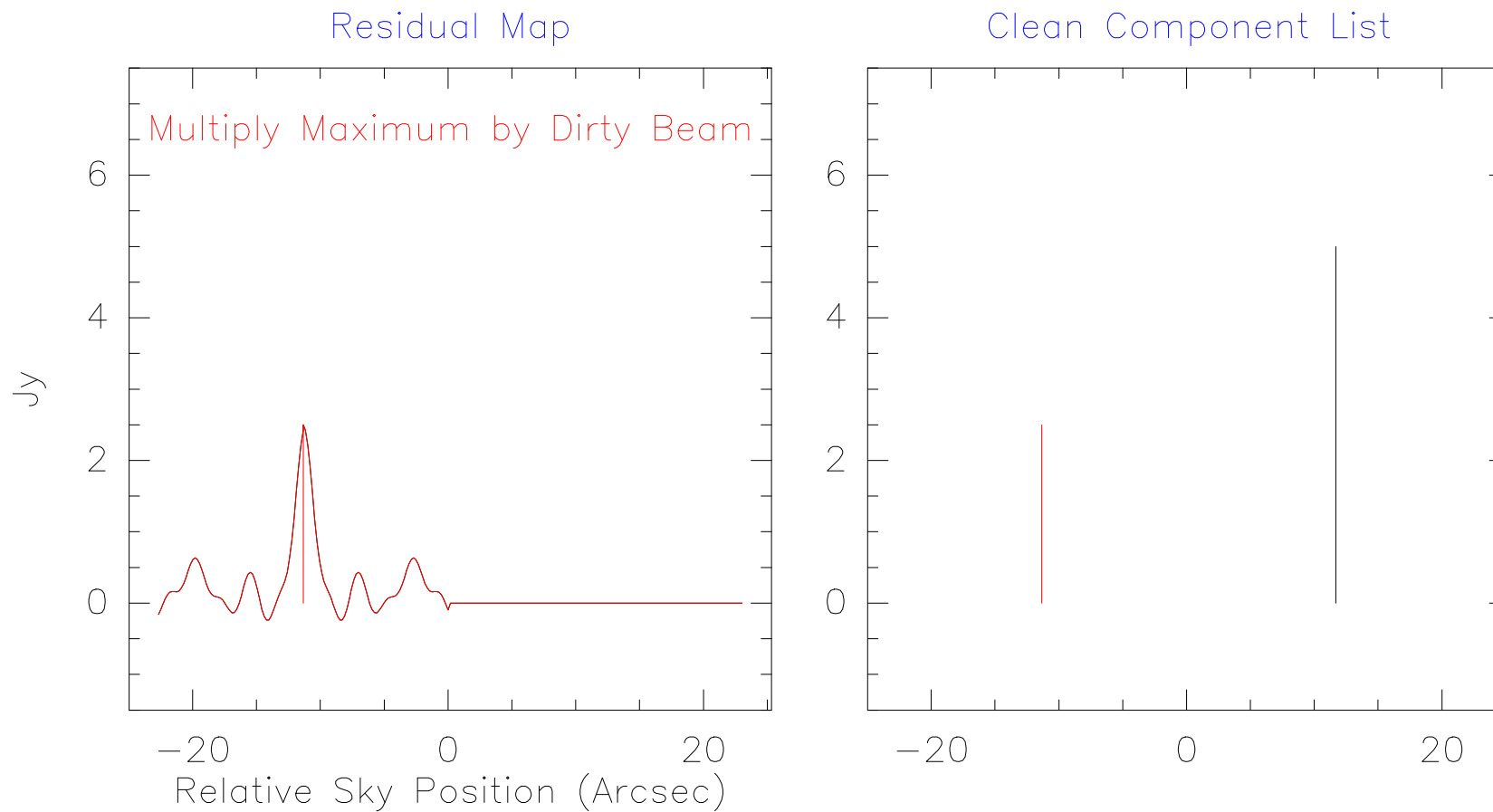
Deconvolution: III. The Basic Clean Algorithm

1. First Illustration



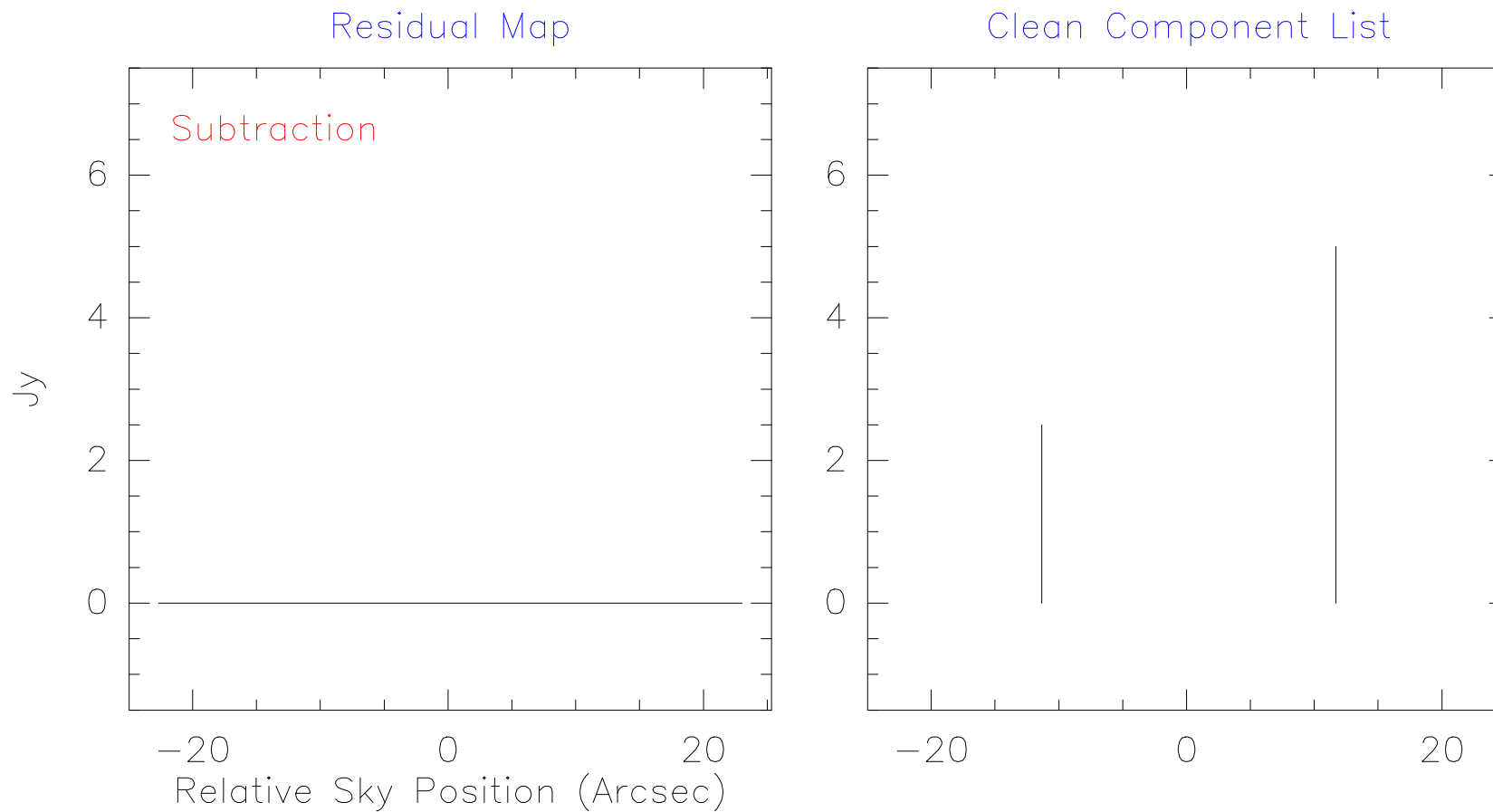
Deconvolution: III. The Basic Clean Algorithm

1. First Illustration



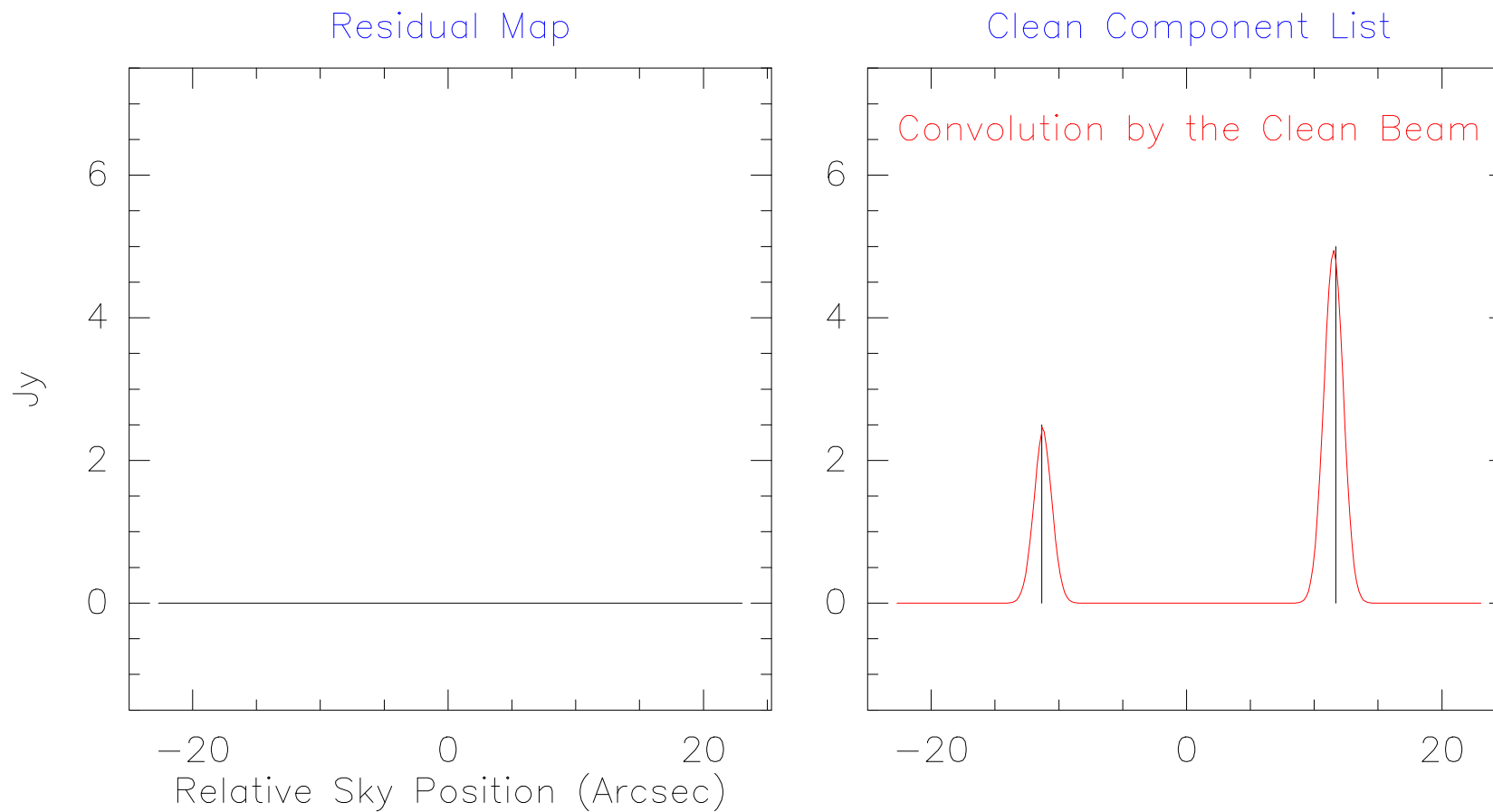
Deconvolution: III. The Basic Clean Algorithm

1. First Illustration



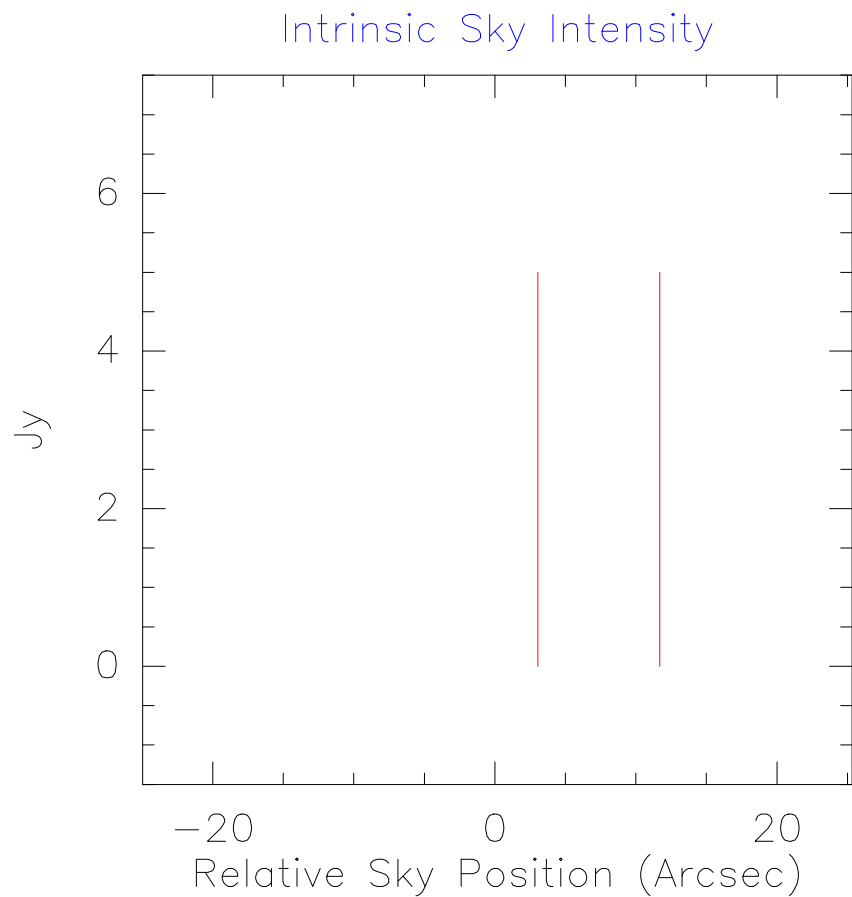
Deconvolution: III. The Basic Clean Algorithm

1. First Illustration



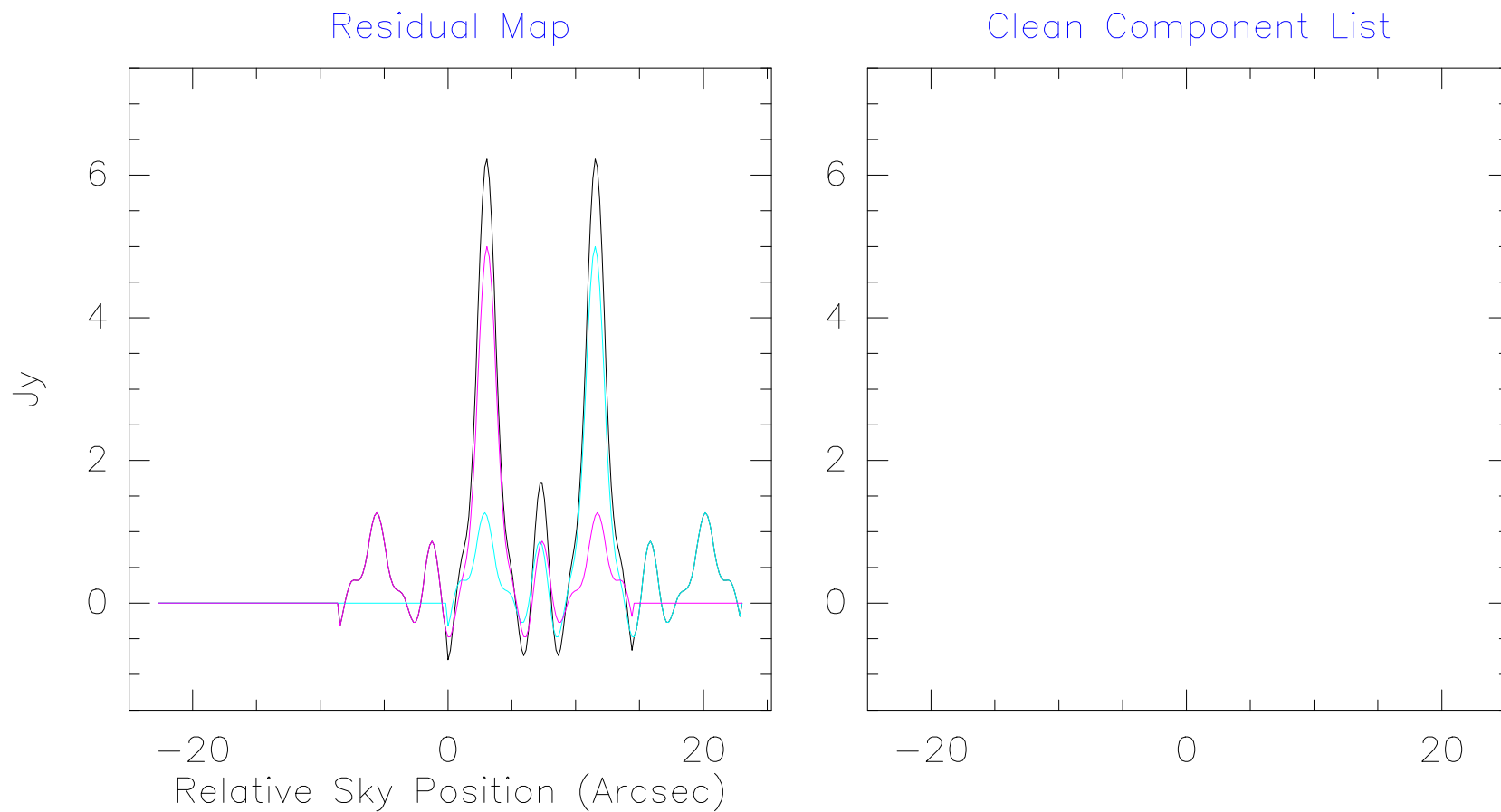
Deconvolution: III. The Basic Clean Algorithm

2. Second Illustration



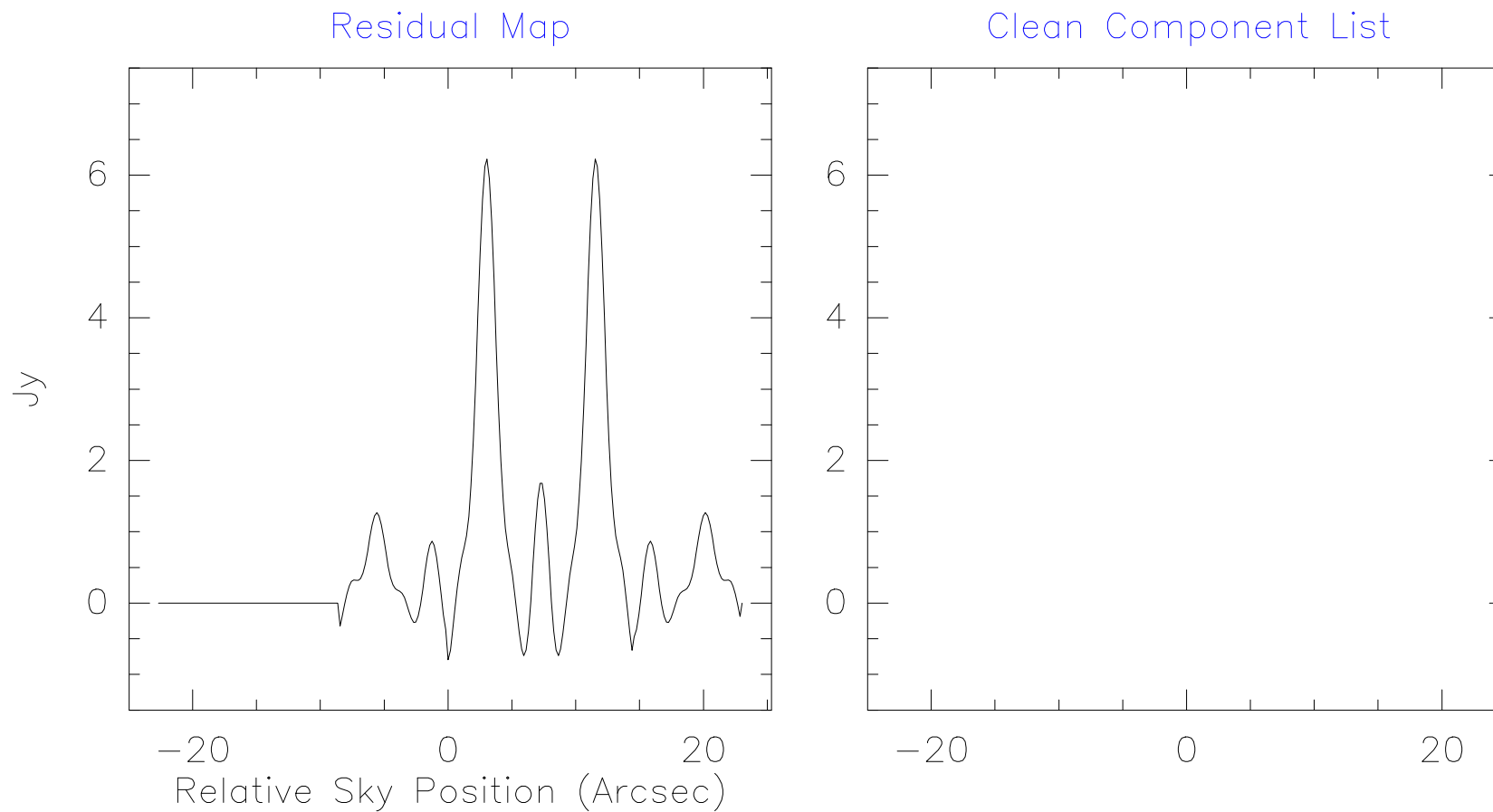
Deconvolution: III. The Basic Clean Algorithm

2. Second Illustration



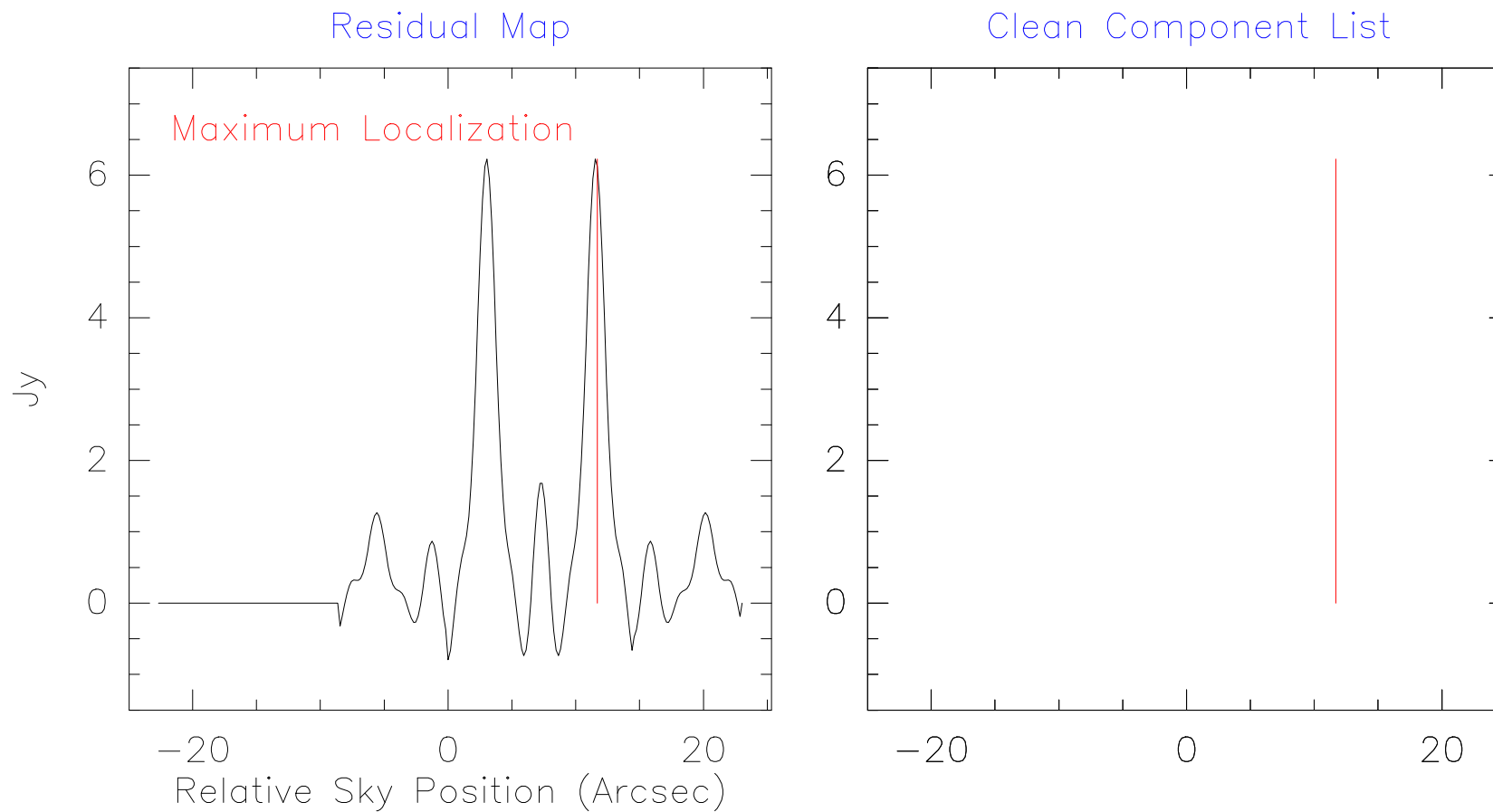
Deconvolution: III. The Basic Clean Algorithm

2. Second Illustration



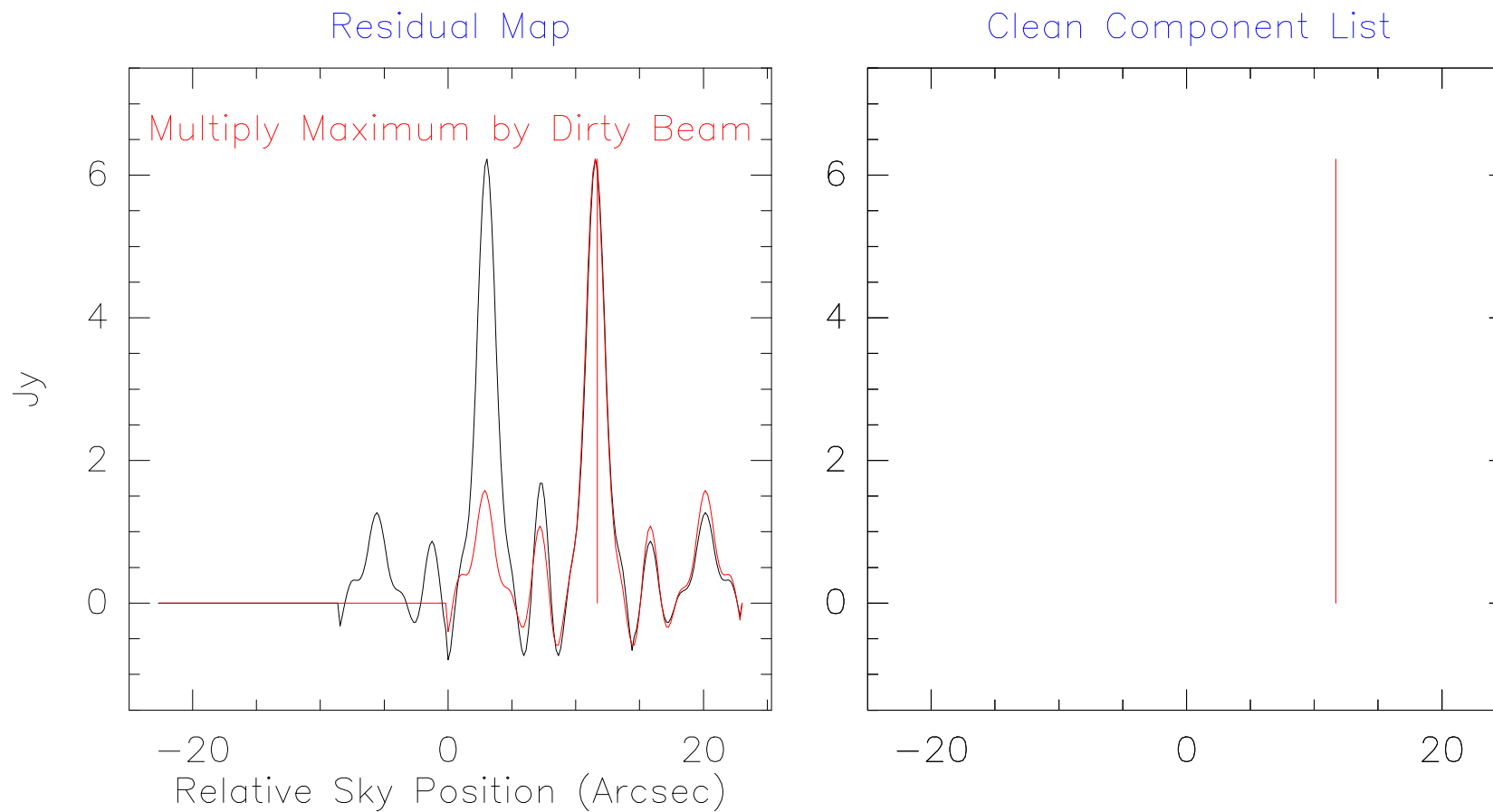
Deconvolution: III. The Basic Clean Algorithm

2. Second Illustration



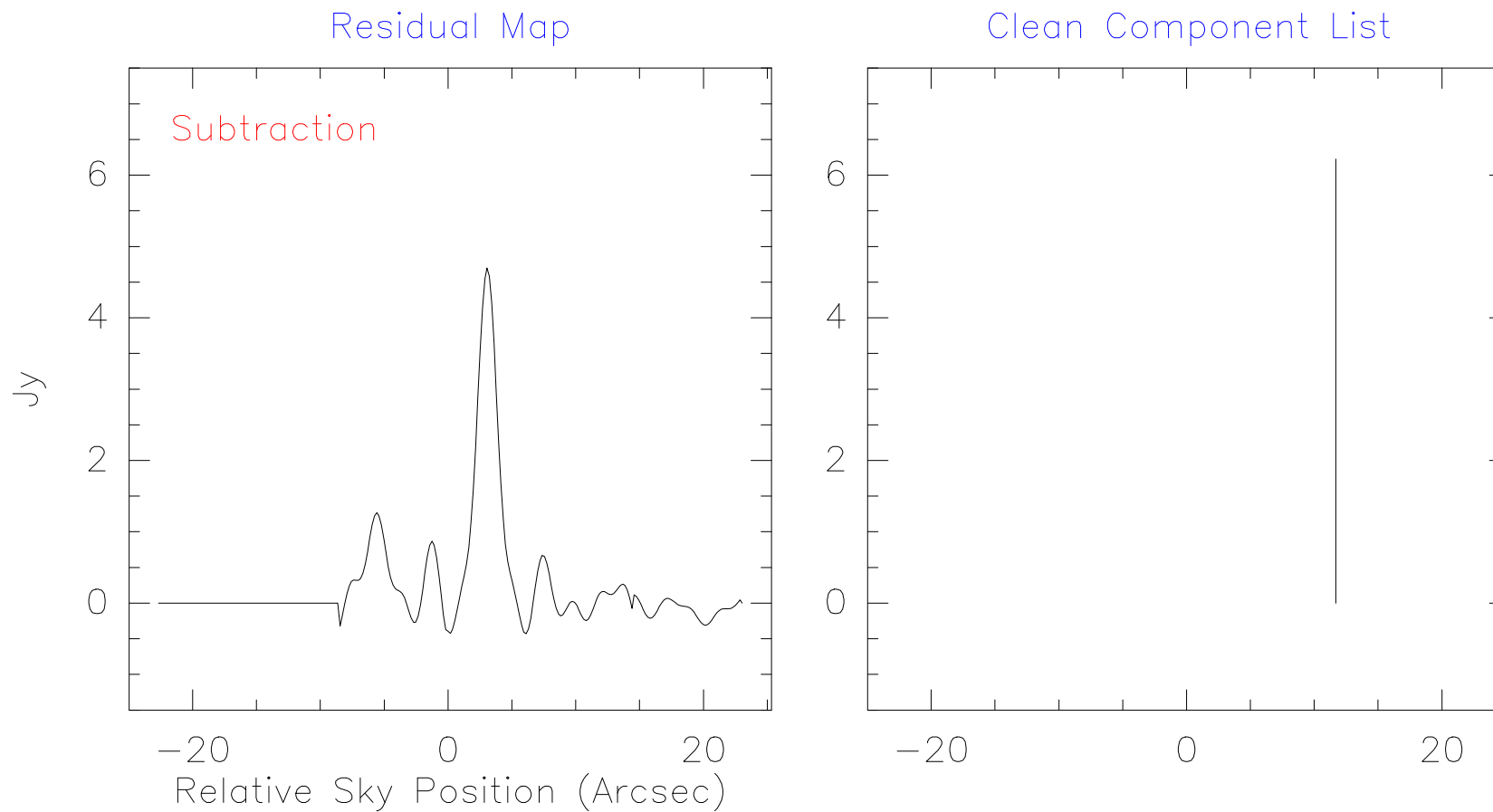
Deconvolution: III. The Basic Clean Algorithm

2. Second Illustration



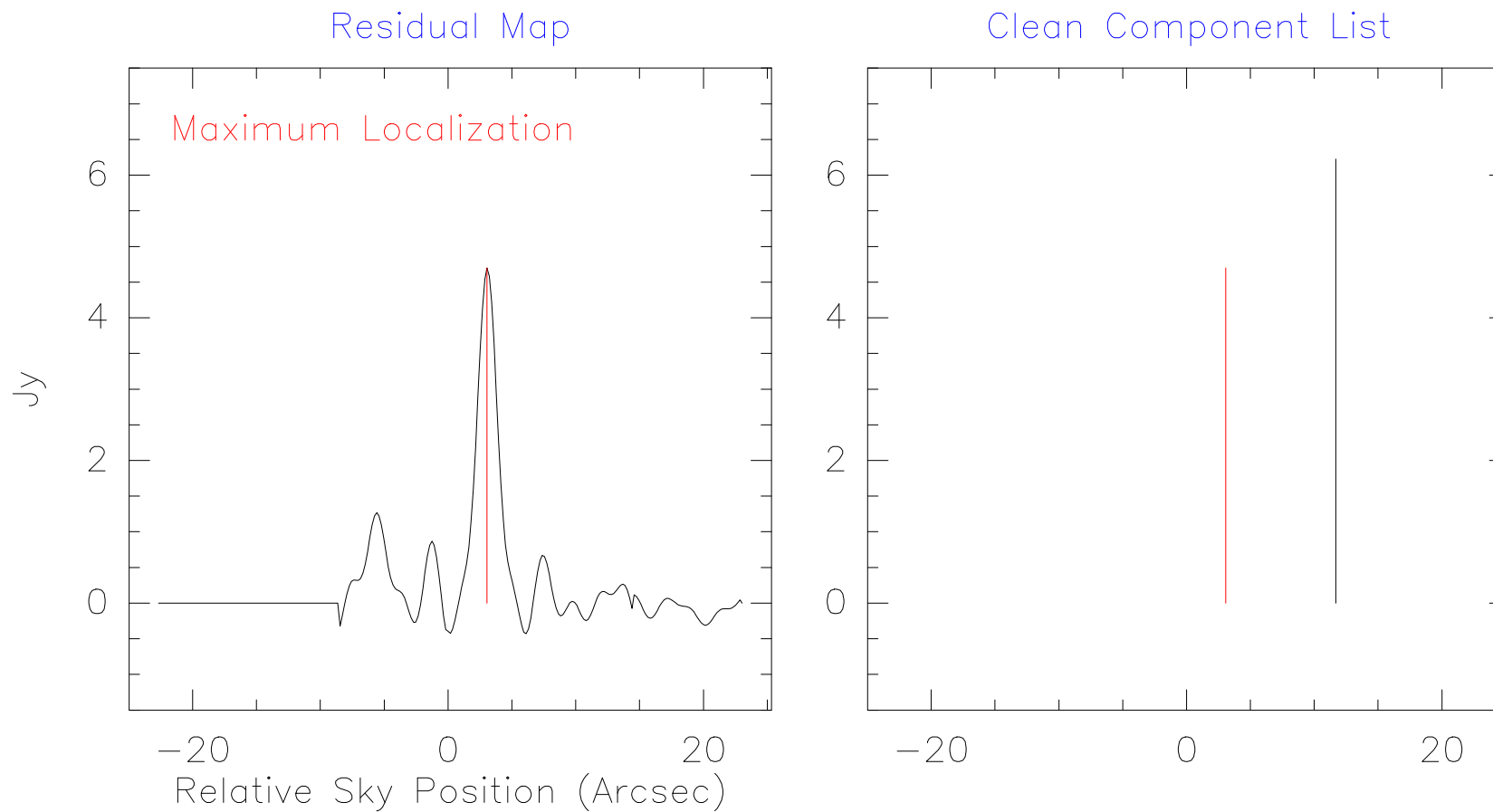
Deconvolution: III. The Basic Clean Algorithm

2. Second Illustration



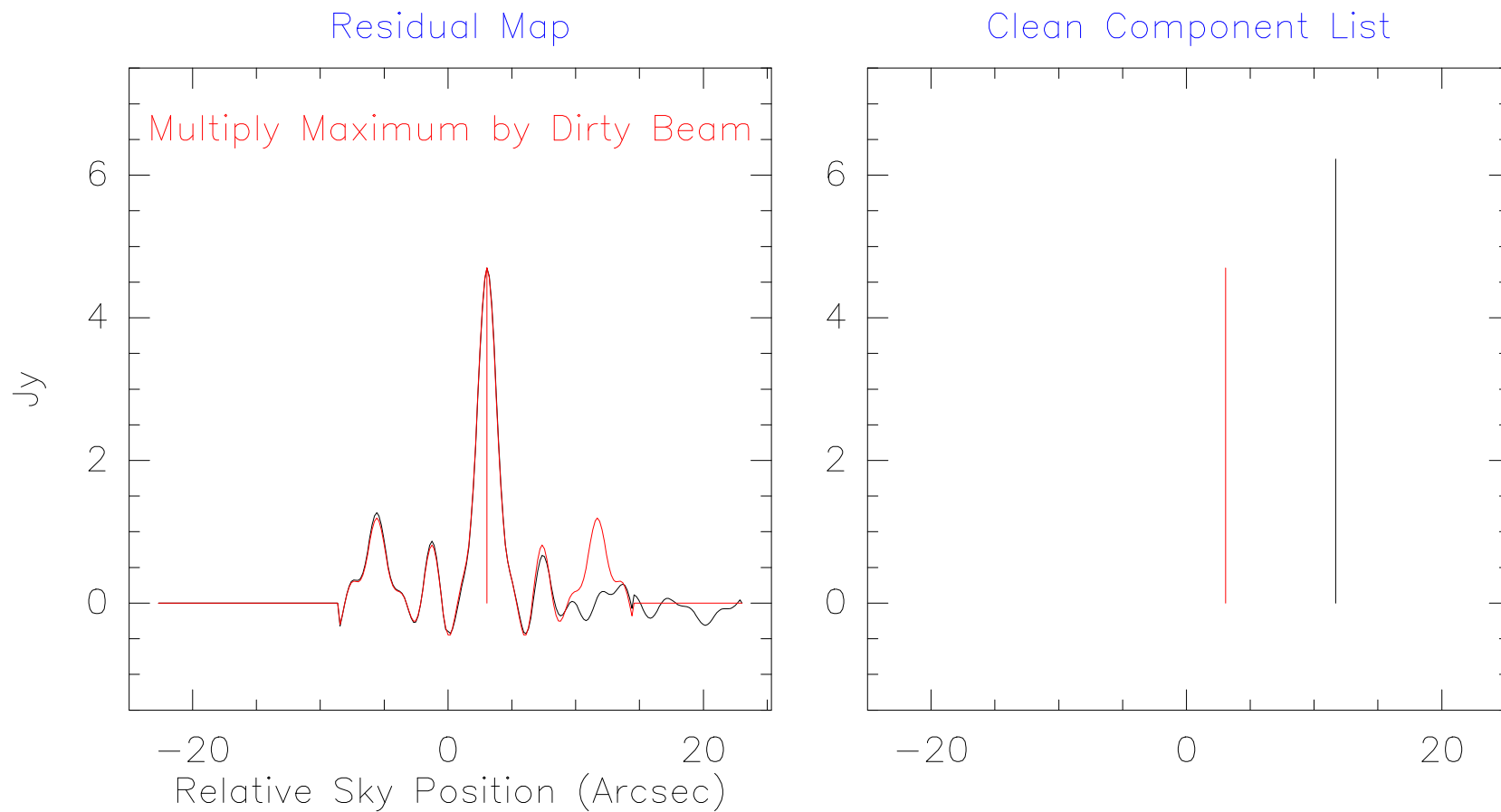
Deconvolution: III. The Basic Clean Algorithm

2. Second Illustration



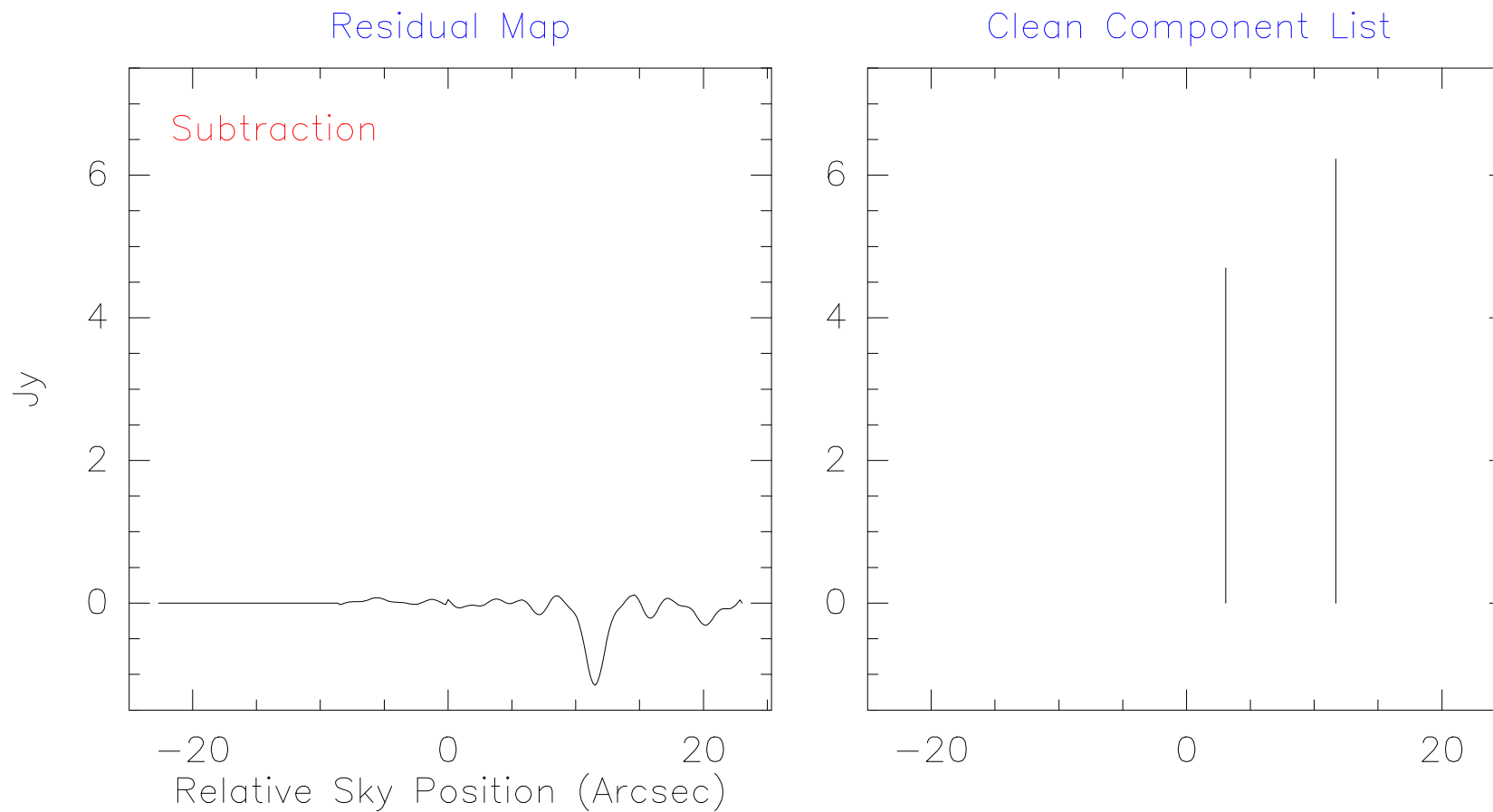
Deconvolution: III. The Basic Clean Algorithm

2. Second Illustration



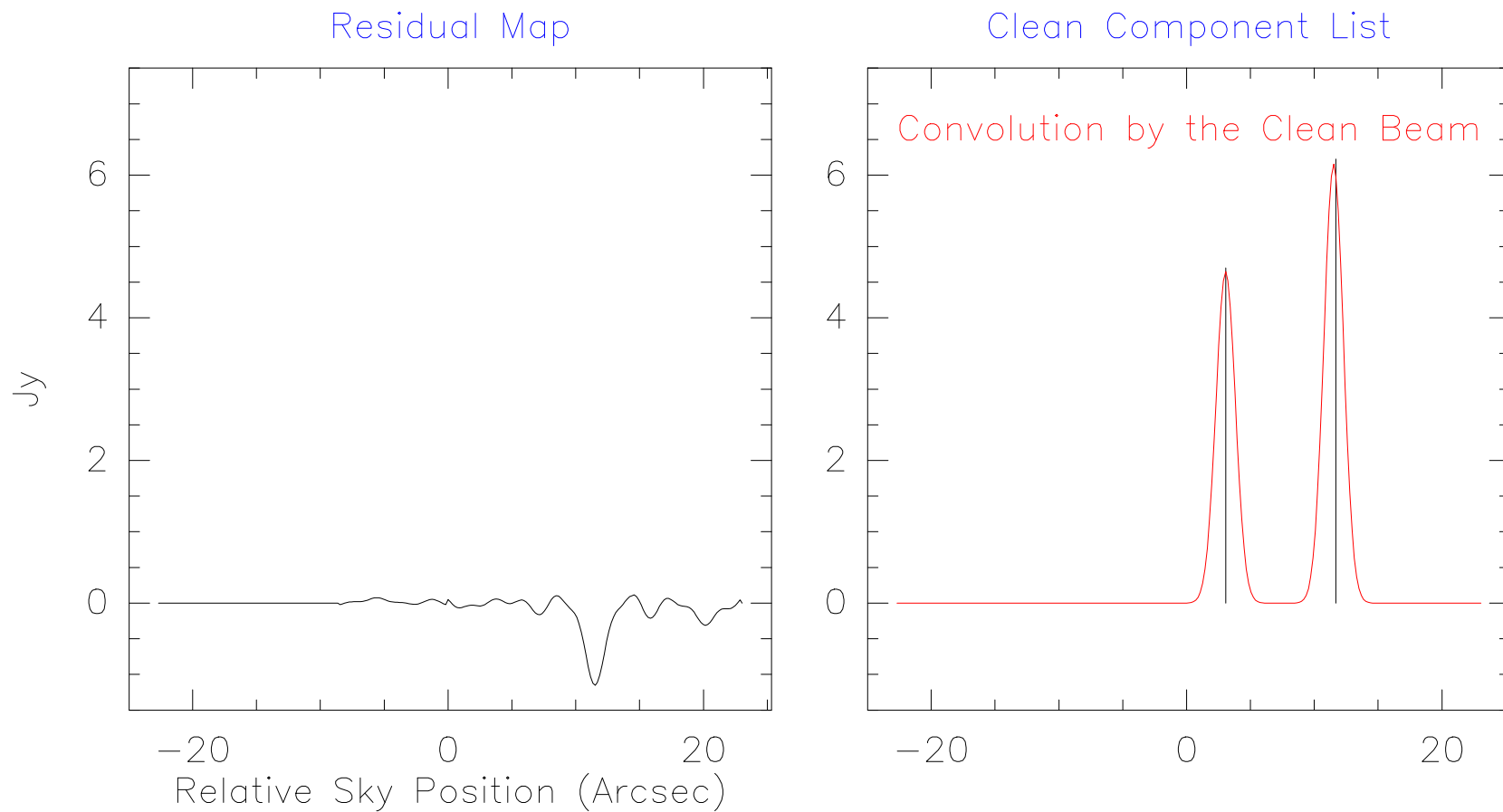
Deconvolution: III. The Basic Clean Algorithm

2. Second Illustration



Deconvolution: III. The Basic Clean Algorithm

2. Second Illustration



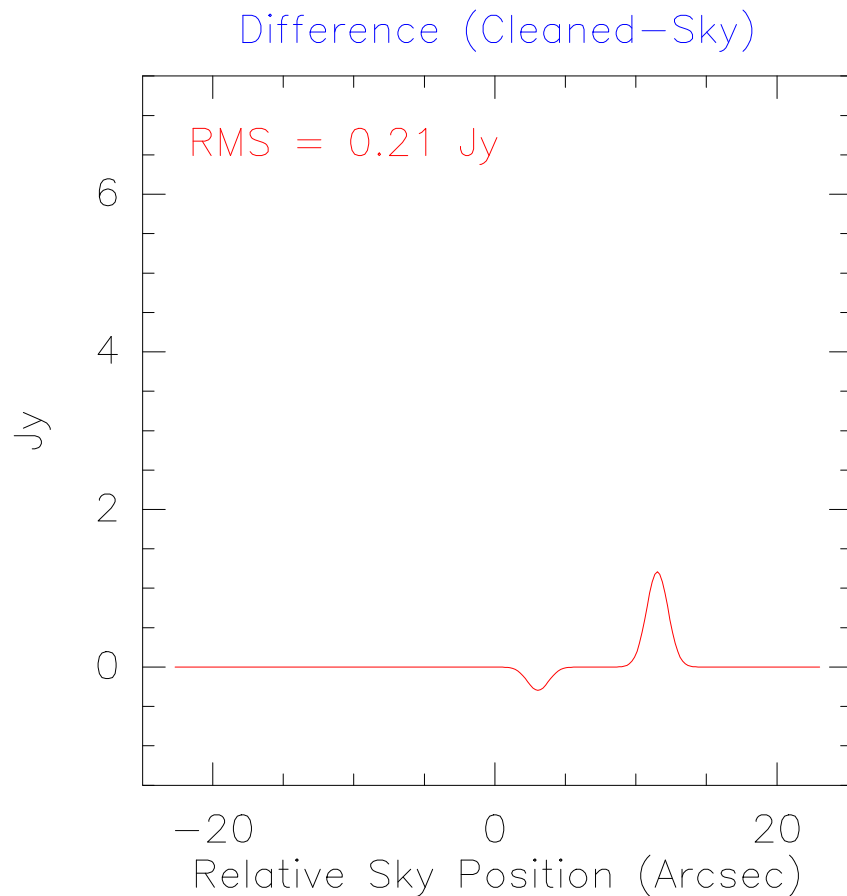
Deconvolution: III. The Basic Clean Algorithm

3. Little Secrets

Convergence:

Too superficial cleaning \Rightarrow Approximate results.

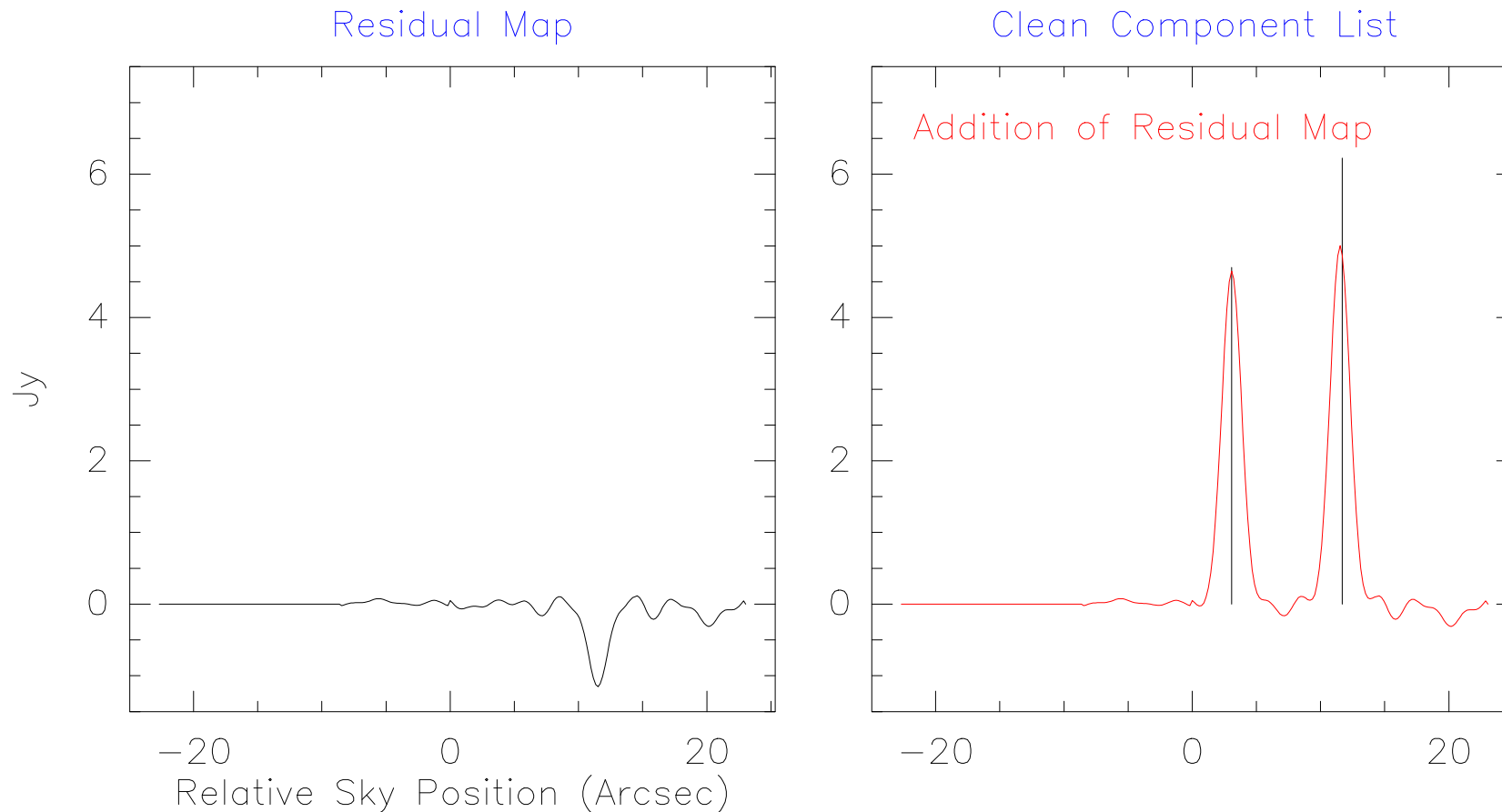
Too deep cleaning \Rightarrow Divergence.



Deconvolution: III. The Basic Clean Algorithm

3. Little Secrets

Addition of residual map:
Improvement when convergence **not** reached;
Noise estimation.

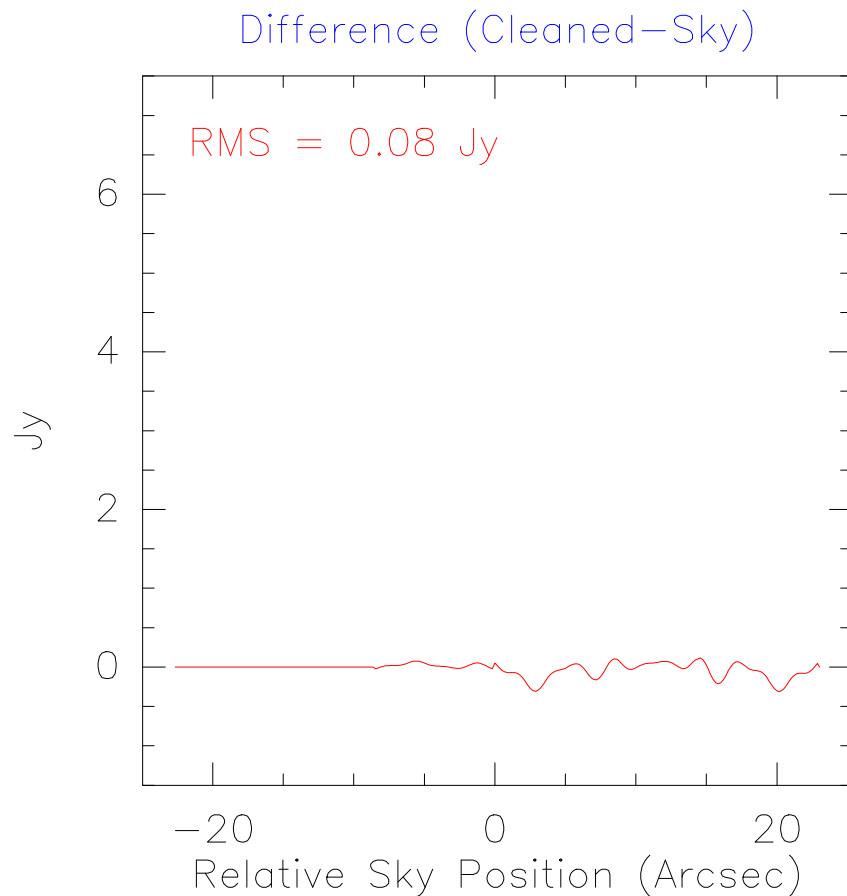


Deconvolution: III. The Basic Clean Algorithm

3. Little Secrets

Addition of residual map:

Improvement when convergence **not** reached;
Noise estimation.



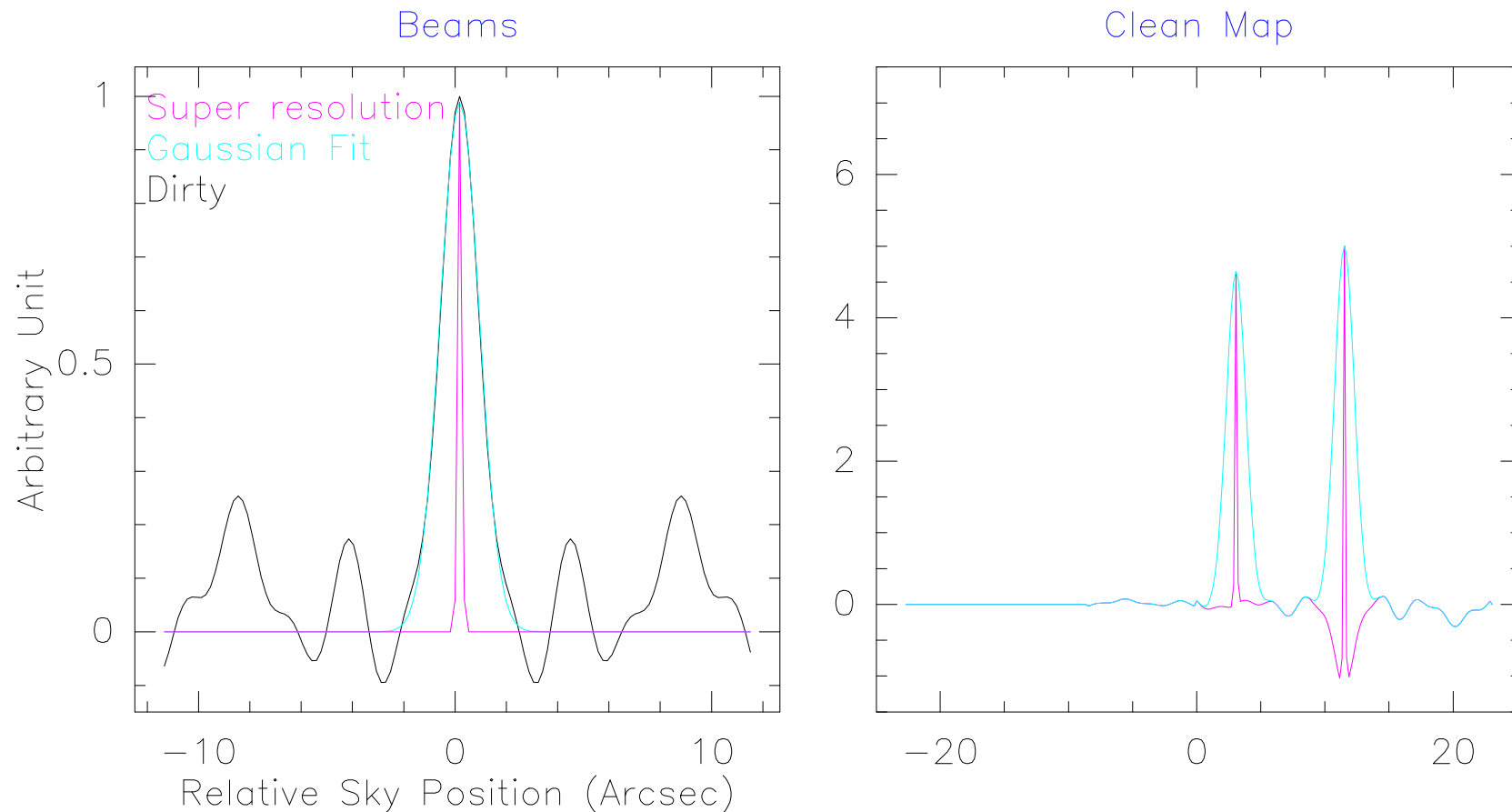
Deconvolution: III. The Basic Clean Algorithm

3. Little Secrets

Choice of clean beam:

Gaussian of FWHM matching the synthesized beam size.

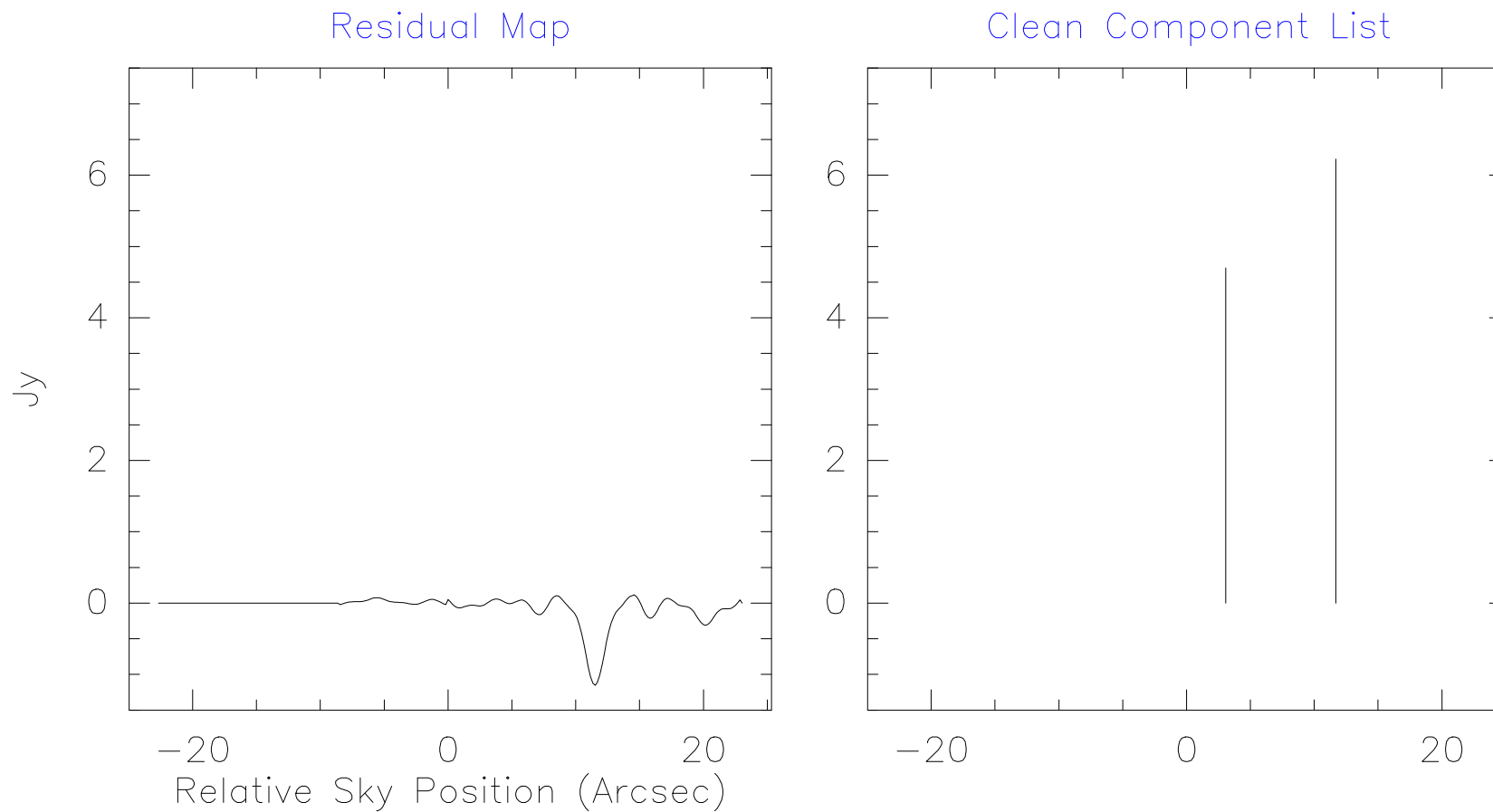
⇒ Super resolution **strongly** discouraged.



Deconvolution: III. The Basic Clean Algorithm

3. Little Secrets

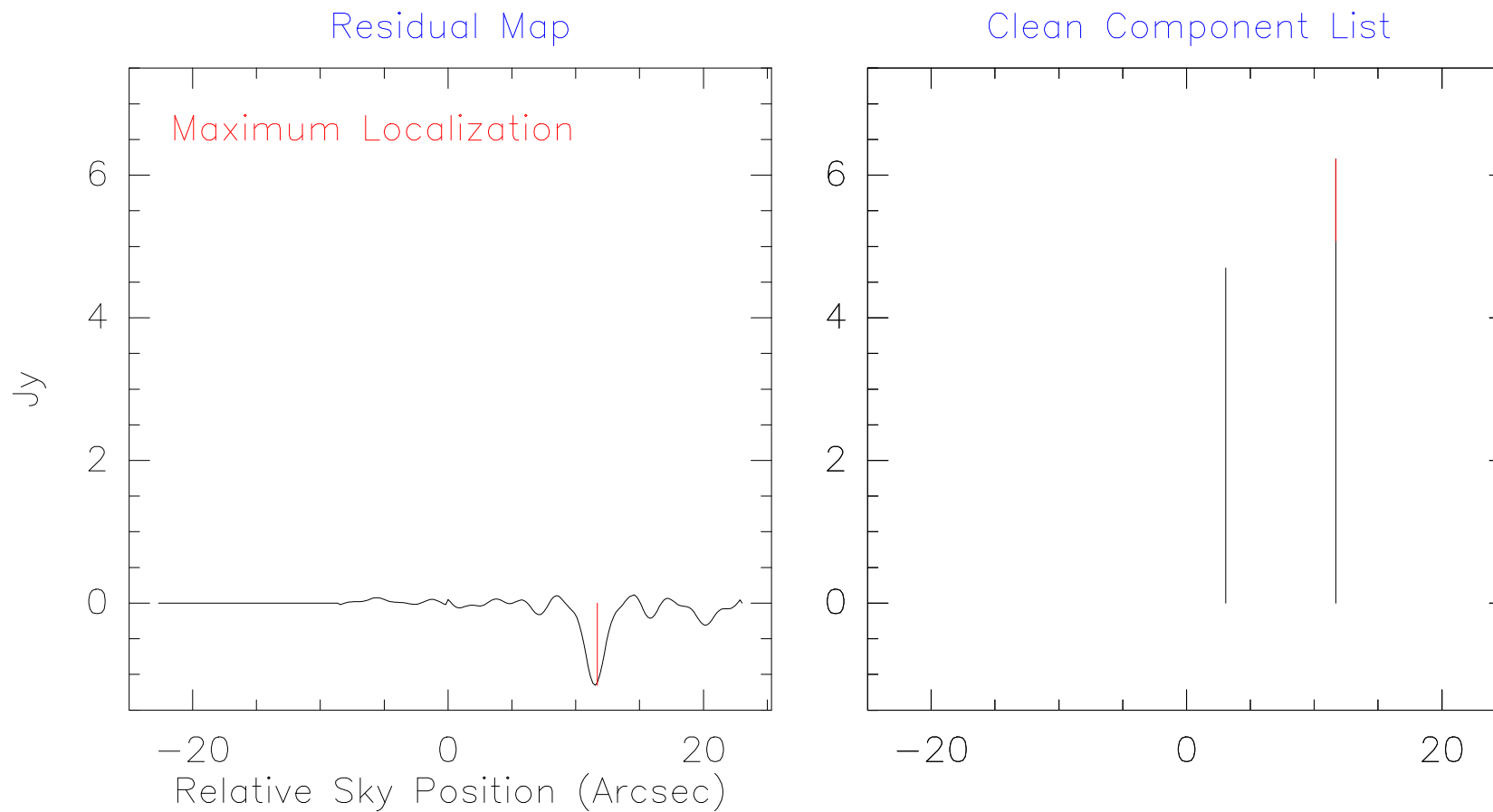
Negative clean components are mandatory.



Deconvolution: III. The Basic Clean Algorithm

3. Little Secrets

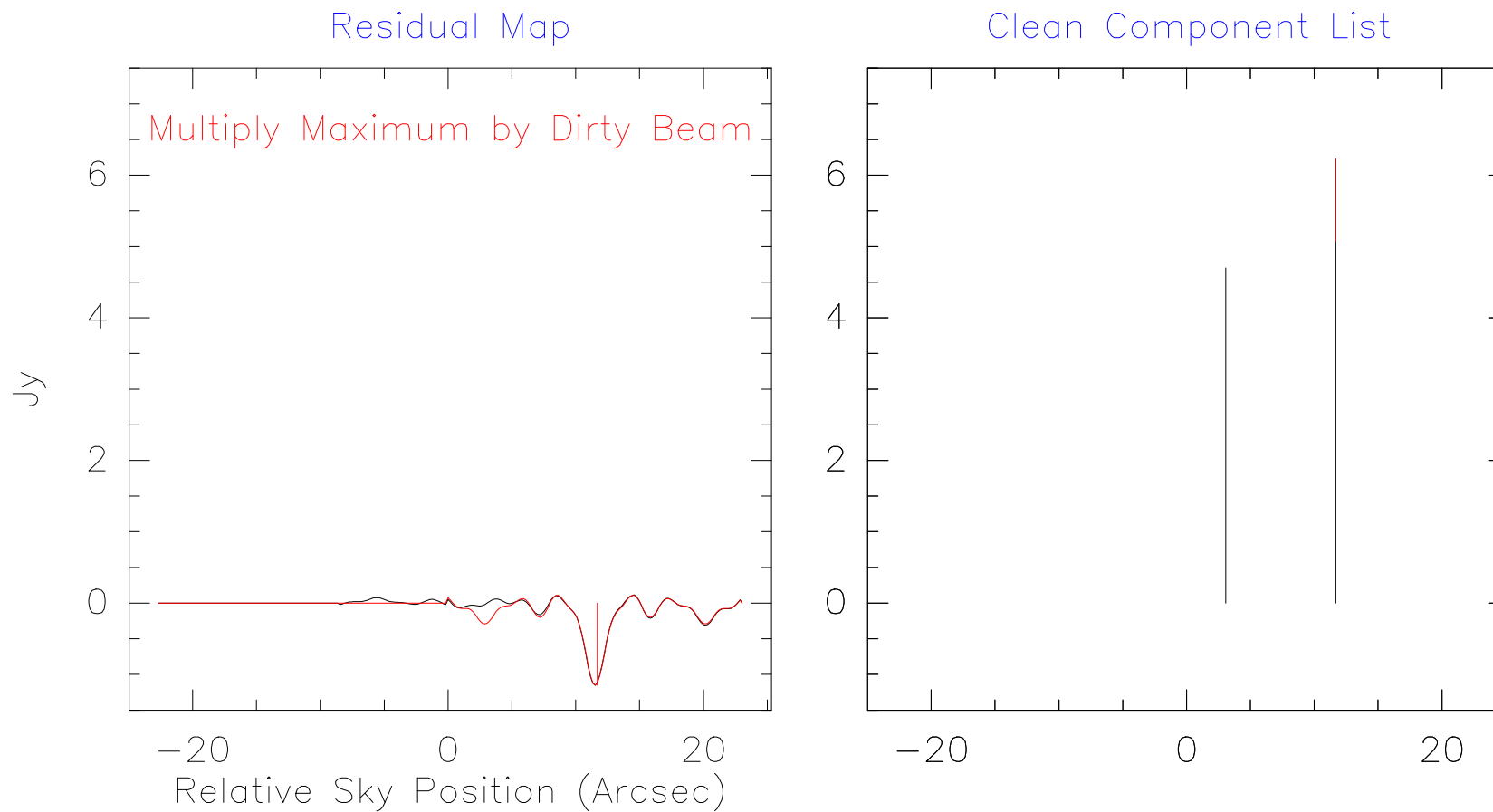
Negative clean components are mandatory.



Deconvolution: III. The Basic Clean Algorithm

3. Little Secrets

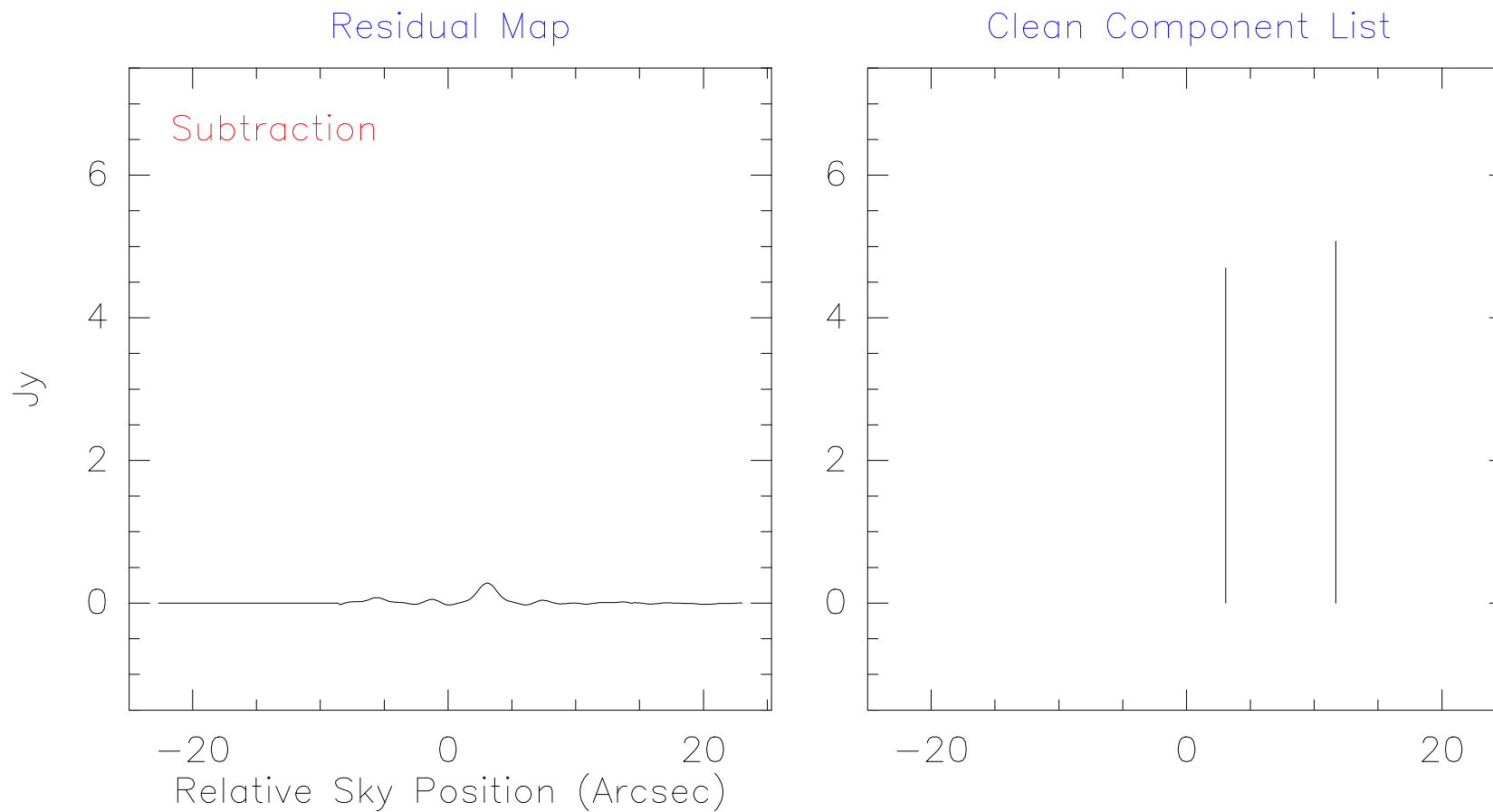
Negative clean components are mandatory.



Deconvolution: III. The Basic Clean Algorithm

3. Little Secrets

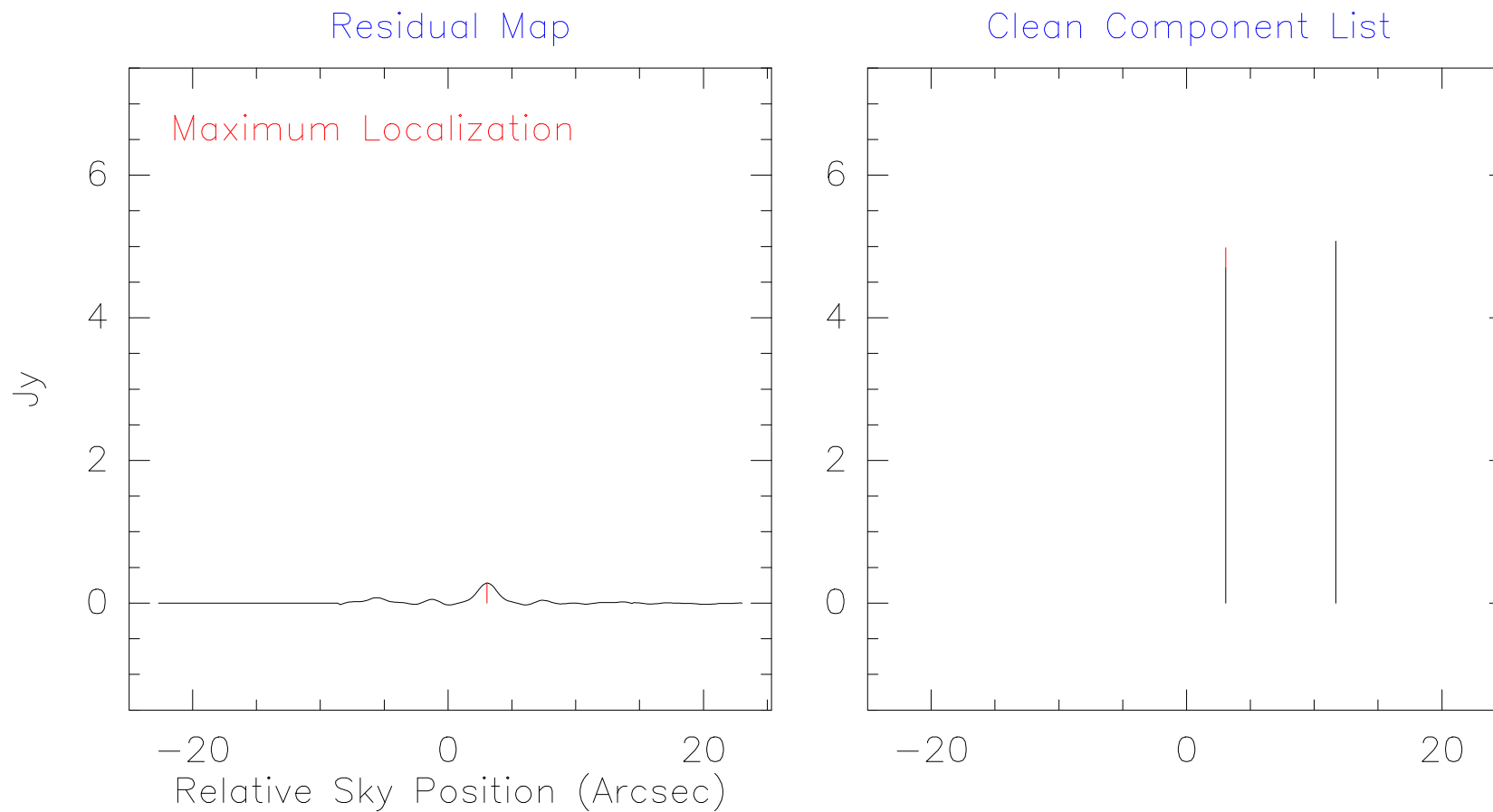
Negative clean components are mandatory.



Deconvolution: III. The Basic Clean Algorithm

3. Little Secrets

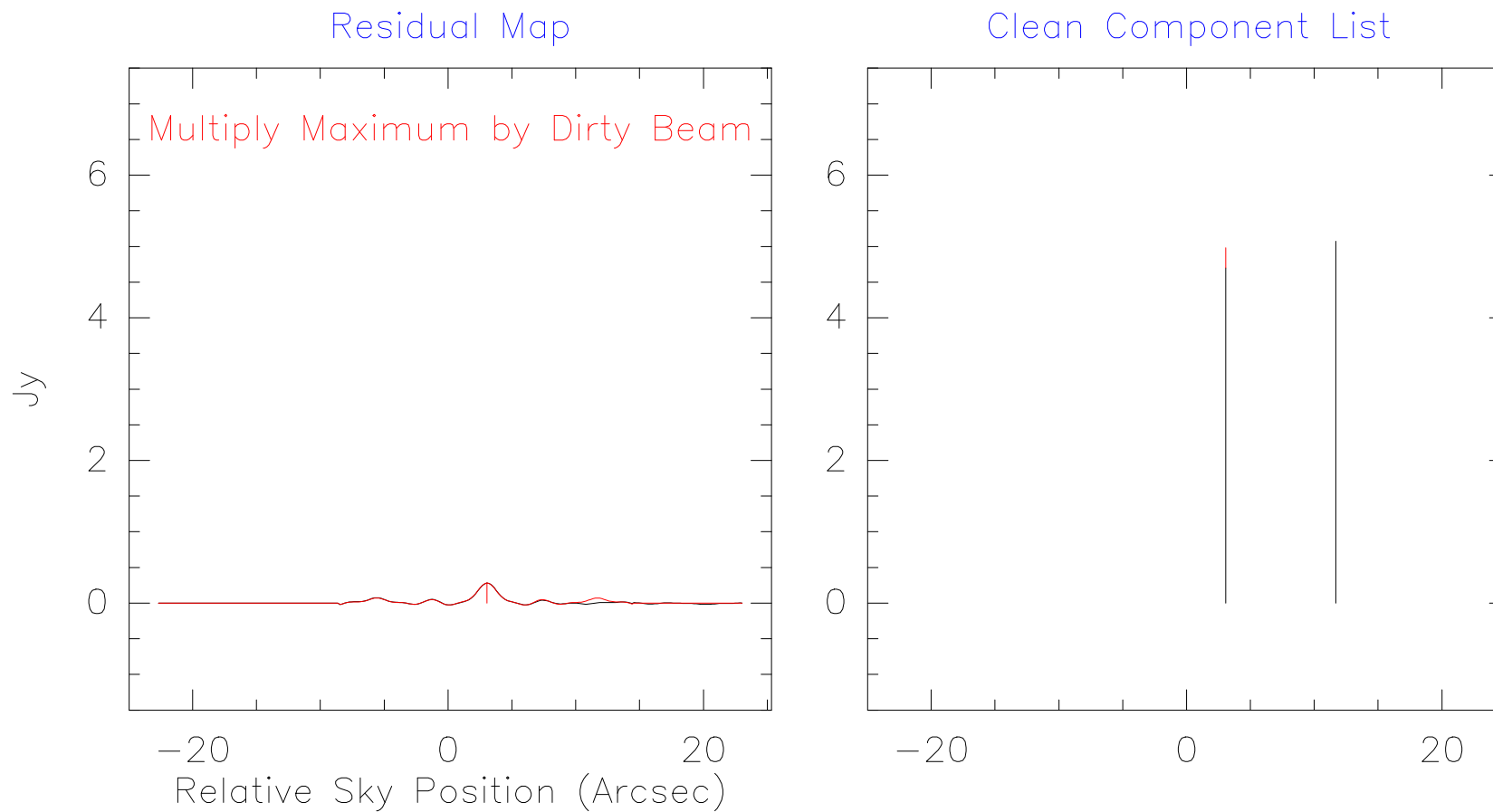
Negative clean components are mandatory.



Deconvolution: III. The Basic Clean Algorithm

3. Little Secrets

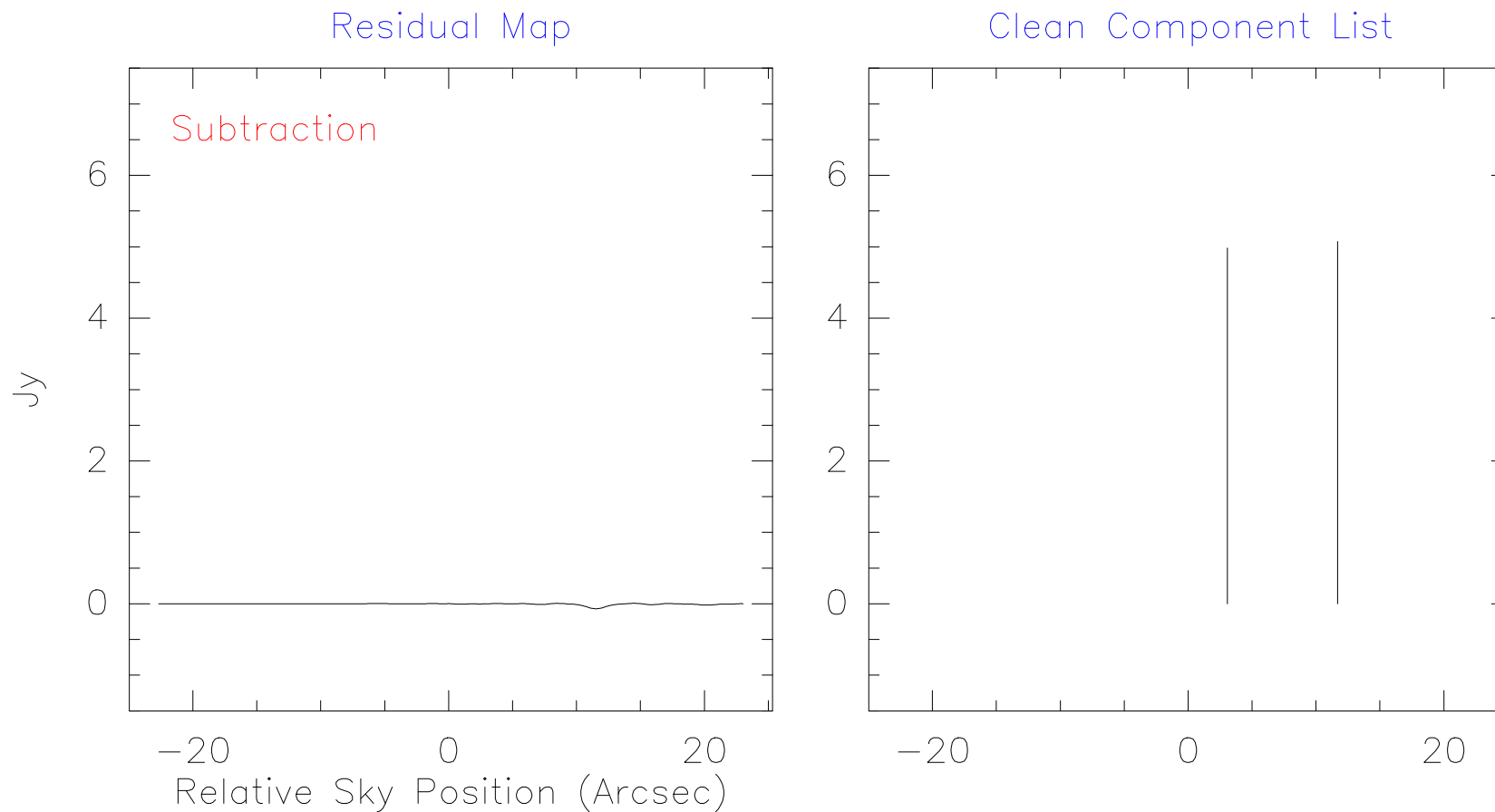
Negative clean components are mandatory.



Deconvolution: III. The Basic Clean Algorithm

3. Little Secrets

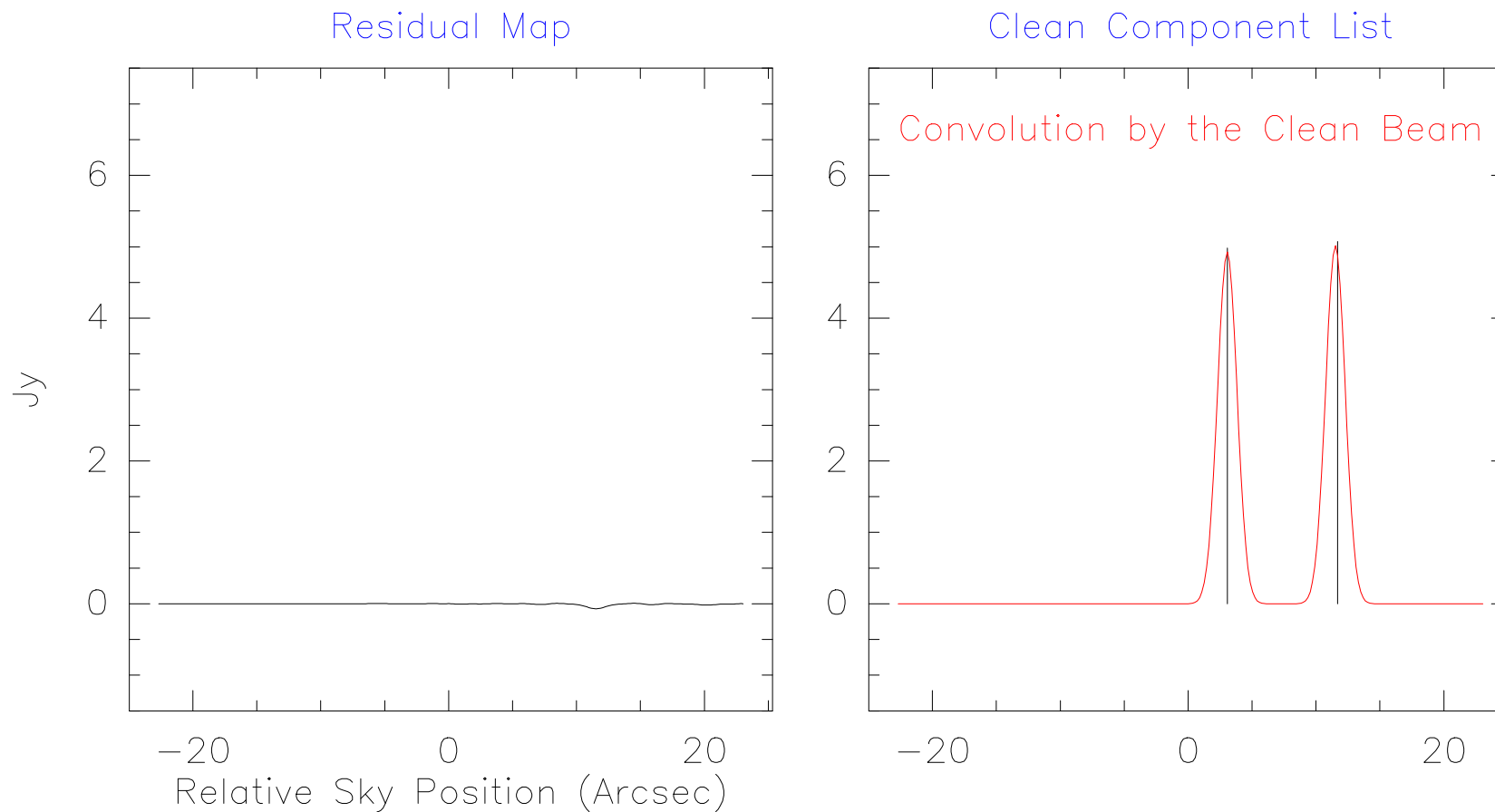
Negative clean components are mandatory.



Deconvolution: III. The Basic Clean Algorithm

3. Little Secrets

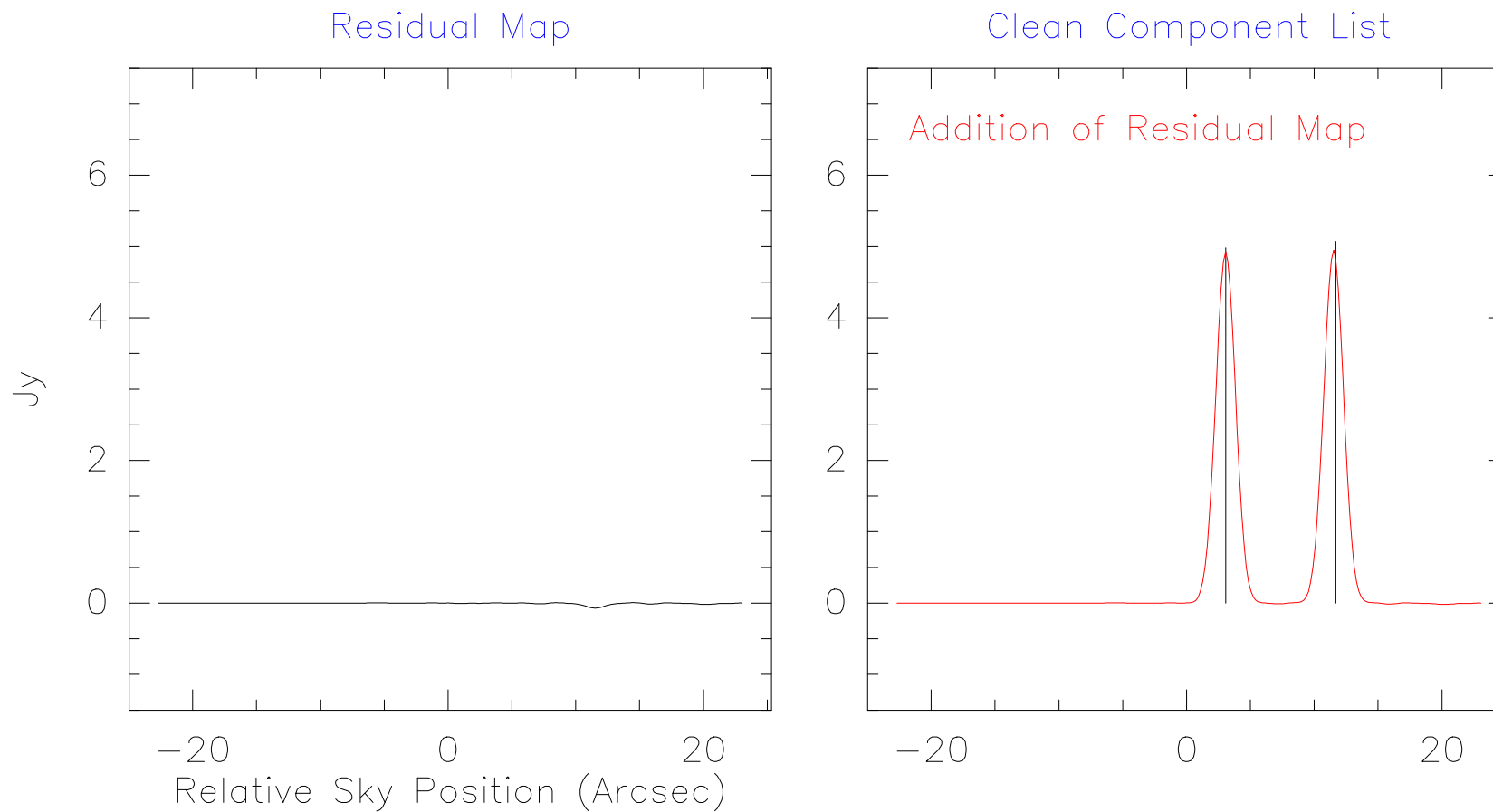
Negative clean components are mandatory.



Deconvolution: III. The Basic Clean Algorithm

3. Little Secrets

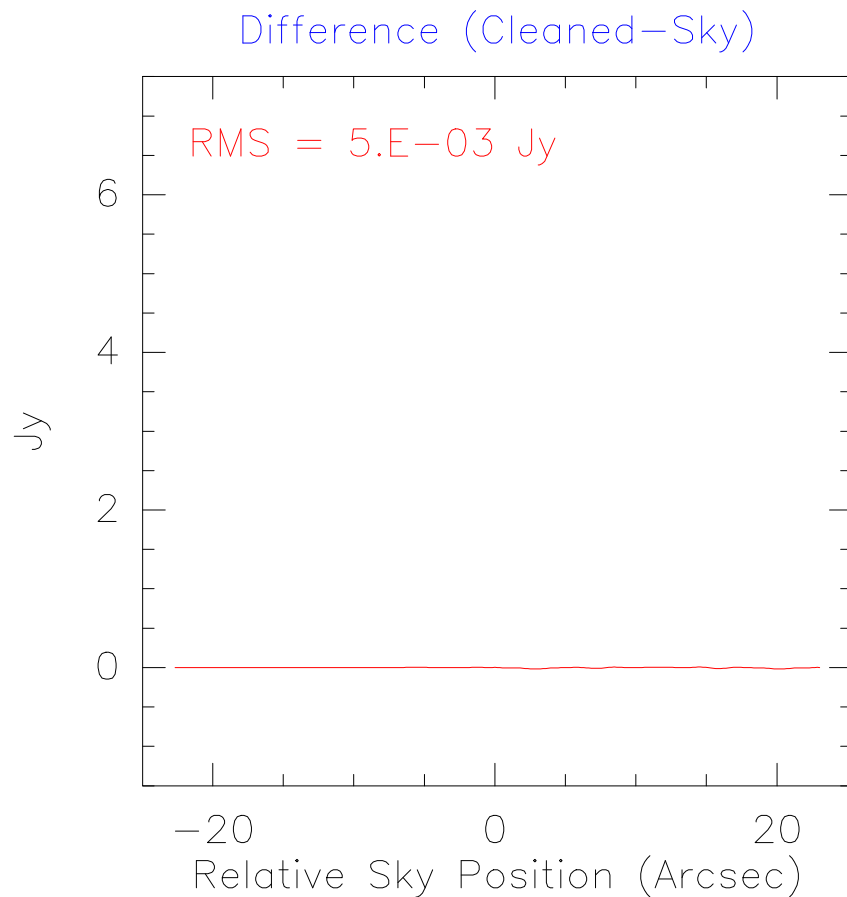
Negative clean components are mandatory.



Deconvolution: III. The Basic Clean Algorithm

3. Little Secrets

Negative clean components are mandatory.



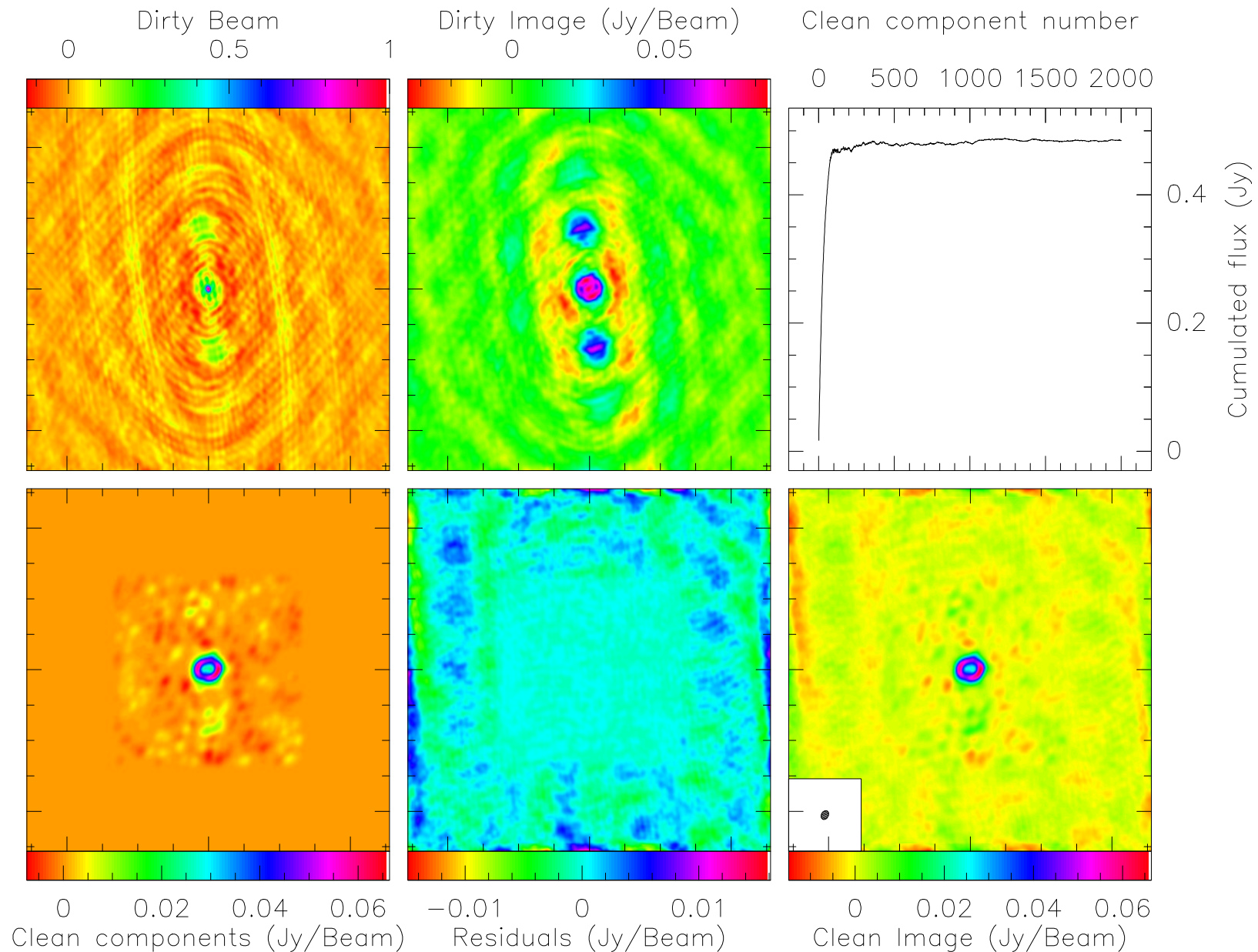
Deconvolution: III. The Basic Clean Algorithm

4. Other Little Secrets

- Stopping criteria:
 - Total number of Clean components;
 - $|I_{\max}| < \text{fraction of noise (when noise limited)}$;
 - $|I_{\max}| < \text{fraction of dirty map max (when dynamic limited)}$.
- Loop gain: Good results when $\gamma \sim 0.1 - 0.3$.
- Cleaned region: Only the inner quarter of the dirty image.
- Support: Definition of a region where CLEAN components are searched.
 - *A priori* information \Rightarrow Help CLEAN convergence.
 - But *bias* if support excludes signal regions
 \Rightarrow Be wise!

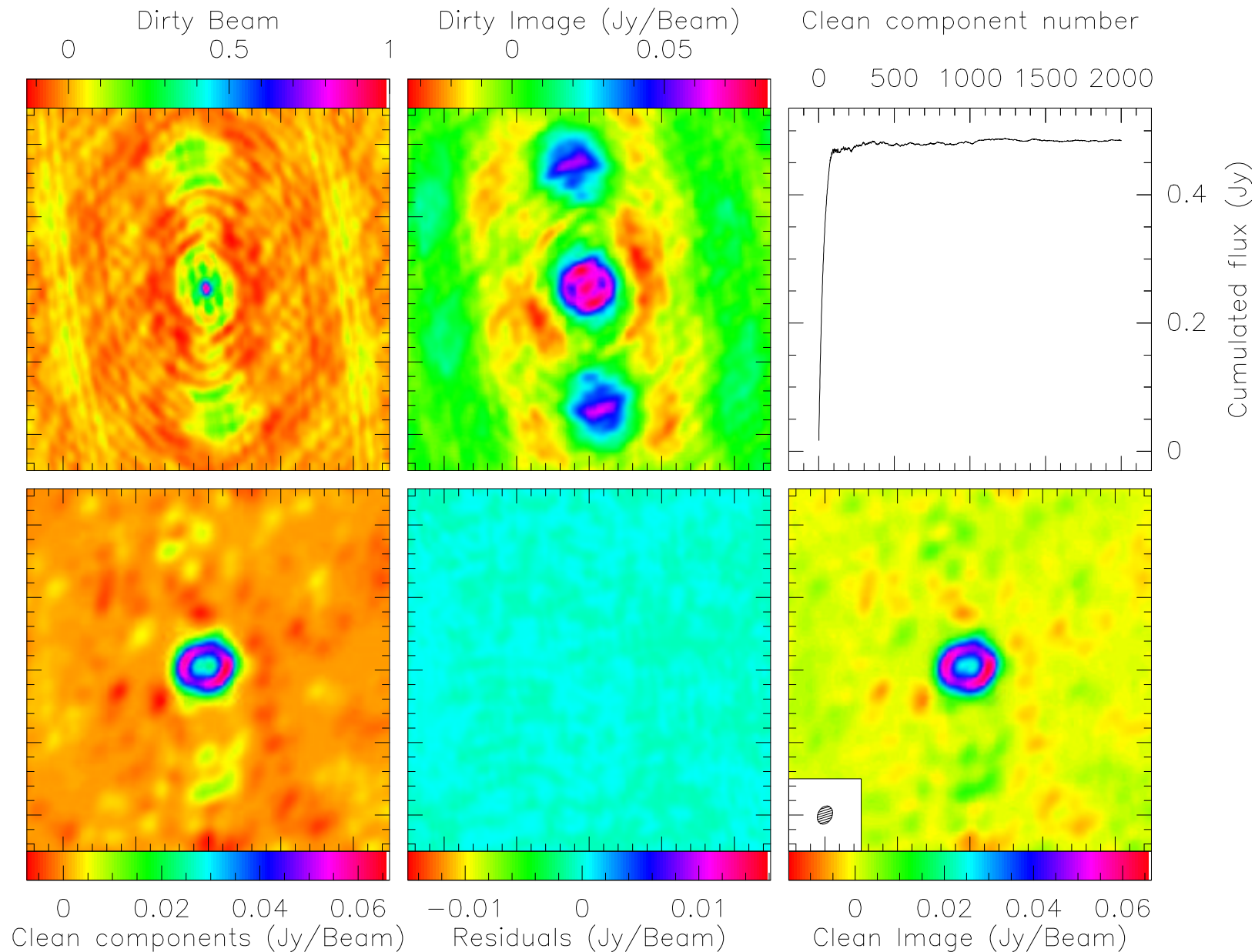
Deconvolution: III. The Basic Clean Algorithm

5. A True Example **without** support



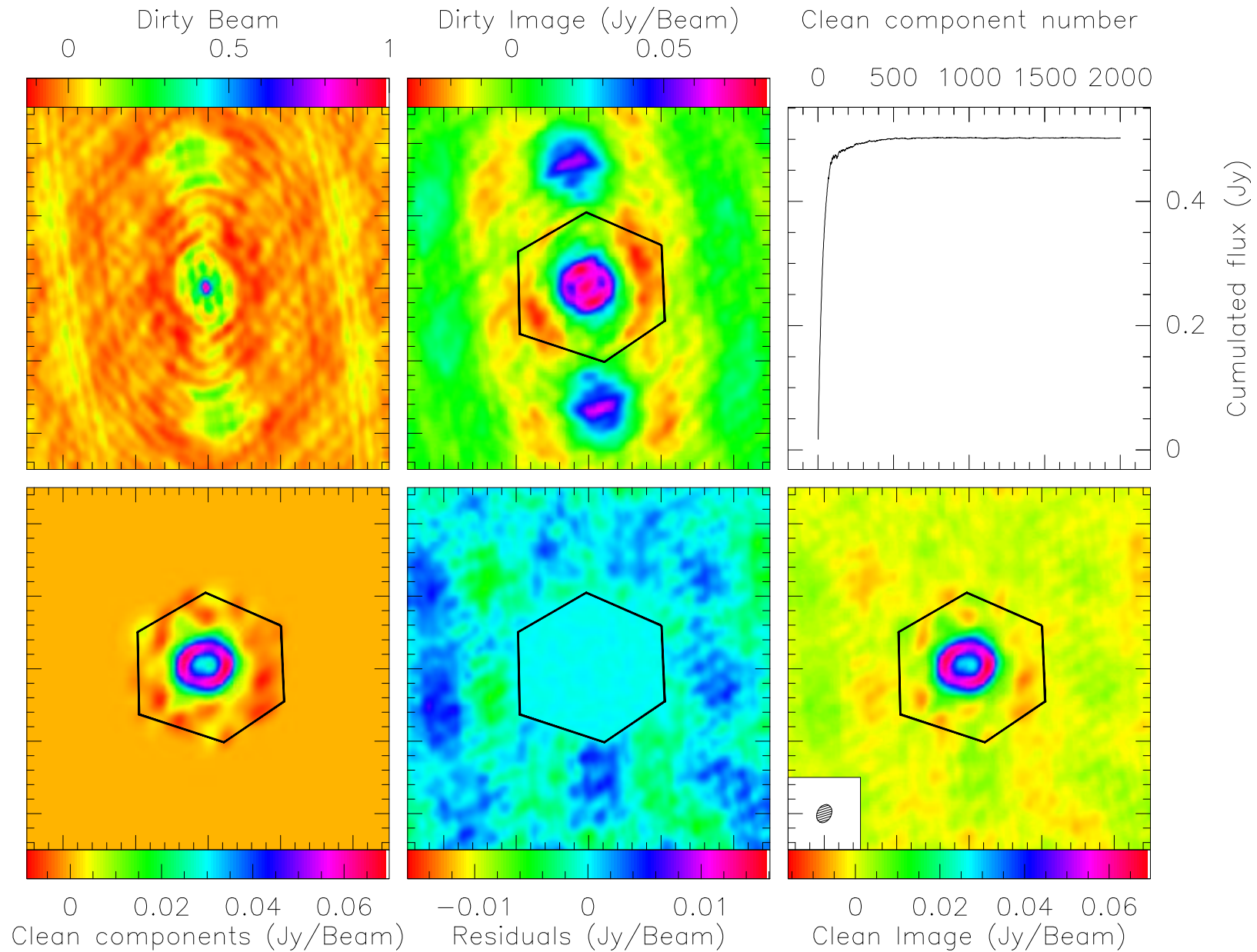
Deconvolution: III. The Basic Clean Algorithm

5. A True Example without support (zoom)



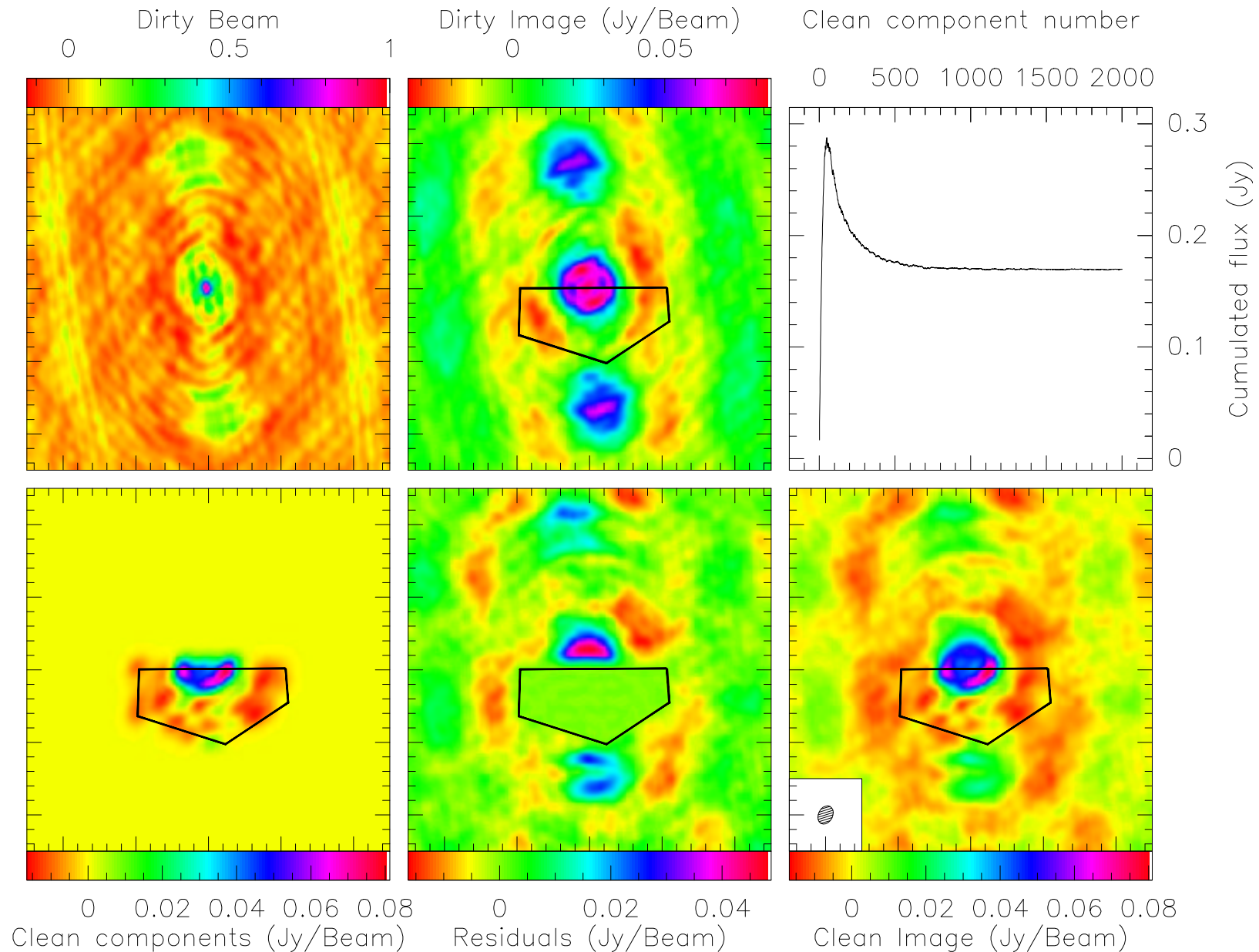
Deconvolution: III. The Basic Clean Algorithm

5. A True Example with **right** support



Deconvolution: III. The Basic Clean Algorithm

5. A True Example with **wrong** support



Deconvolution: IV. CLEAN Variants

Basic:

- HOGBOM (Hogböm 1974)
Robust but slow.

Faster Search Algorithms:

- CLARK (Clark 1980)
Fast but unstable (when sidelobes are high).
- MX (Cotton & Schwab 1984)
Better accuracy (Source removal in the uv plane), but slower (gridding steps repeated).

Deconvolution: IV. CLEAN Variants (continued)

Better Handling of Extended Sources:

- SDI (Steer, Dewdney, Ito 1984)
Created to minimize stripes.
- MRC (Multi-Resolution Clean by Wakker & Schwarz 1988)
Simple multi-resolution approach.
- MULTI (Multi-Scale Clean by Cornwell 1998)
Complex multi-resolution approach.

In practice: Exotic use at PdBI!

Deconvolution: IV. GILDAS Implementation

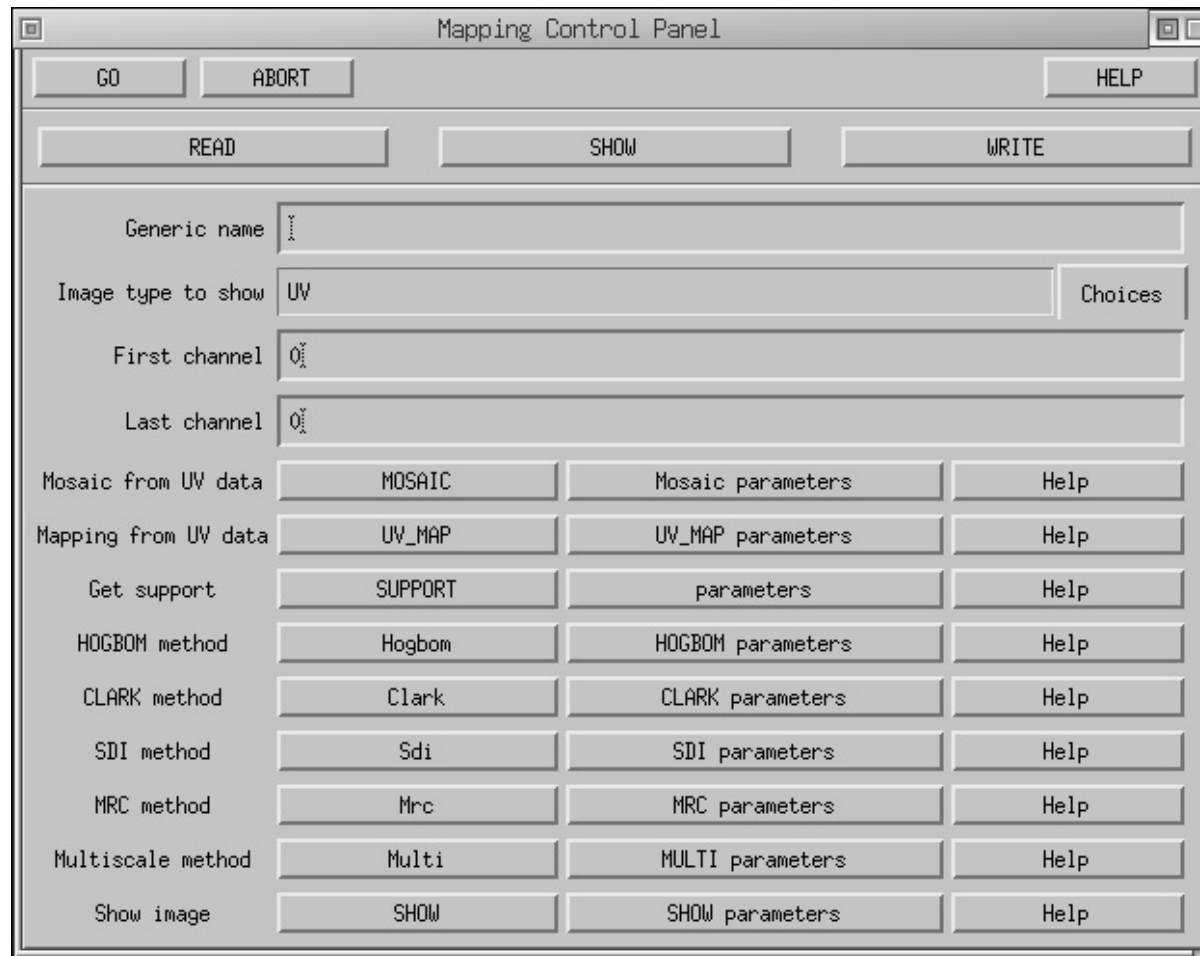
1. MAPPING Command Line

MAPPING> INPUT CLEAN: display CLEAN control parameters.

- Loop gain: **GAIN** (default: 0.2).
- Stopping criteria:
 - Maximum number of iterations: **NITER** (default: 100).
 - Maximum residual amplitude, expressed as fraction of peak intensity: **FRES** (default: 0.05).
 - Maximum residual amplitude, in map units (Jy/Beam): **ARES** (default: 0).
- Support: **BLC** and **TRC** are the Bottom Left Corner and Top Right Corner of a square support in pixel units (default: 0, *i.e.* no support).
- Gaussian clean beam parameters: **MAJOR**, **MINOR**, **ANGLE** (Default: 0, *i.e.* Fit dirty beam).

Deconvolution: IV. GILDAS Implementation

2. MAPPING Window Interface



Deconvolution: IV. Recommended Practices

- Method: Start with CLARK and turn to HOGBOOM in case of problems.
- Support:
 - Start without one.
 - Define one on your first clean image if really needed (*i.e.* difficulties of convergence).
- Stopping criterion:
 - Use a large enough number of iterations to ensure convergence.
 - Clean down to the noise level unless a very strong source is present.
- Misc: Consult an expert until you become one.

Typical MAPPING session

Look at the `mapping-tutorial.map` procedure for details.

```
MAPPING> read uv 1mm
MAPPING> show uv
MAPPING> input uv_map
MAPPING> uv_map
MAPPING> show beam
MAPPING> show dirty 1mm
MAPPING> write beam 1mm
MAPPING> write dirty
MAPPING> input clean
MAPPING> hogbom /flux 0 1
MAPPING> show clean
MAPPING> show residual
MAPPING> write clean 1mm
MAPPING> write residual 1mm
MAPPING> exit
```

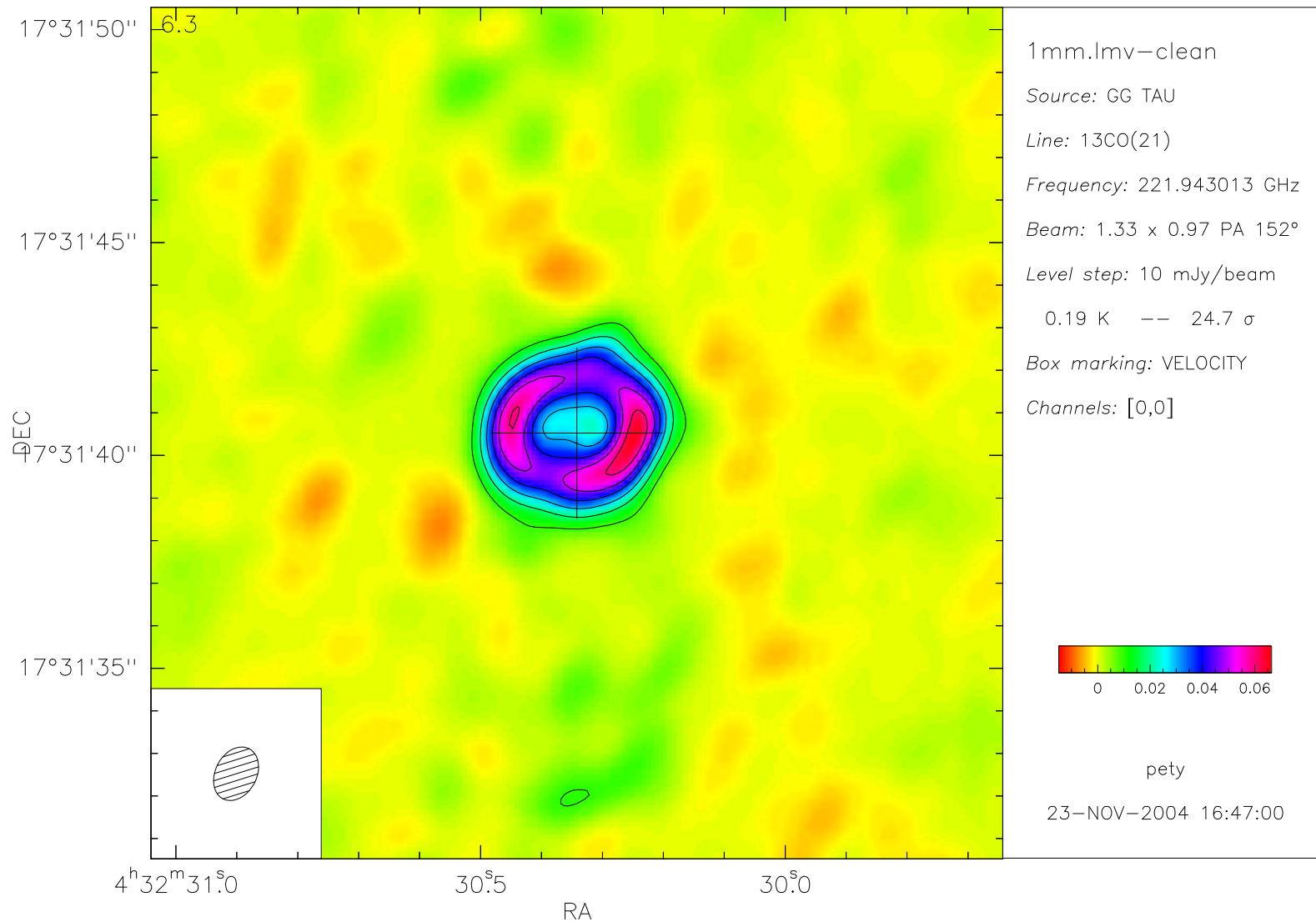
Visualization and Image Analysis

Fourier Transform and Deconvolution:
The two key issues in imaging.

Stage	Implementation
Calibrated Visibilities	
↓ Fourier Transform	UV_STAT, UV_MAP
Dirty beam & image	
↓ Deconvolution	HOGBOM, CLARK
Clean beam & image	
↓ Visualization	GO_BIT, GO_VIEW
↓ Image analysis	GO_NOISE, GO_FLUX, GO_MOMENTS
Physical information on your source	

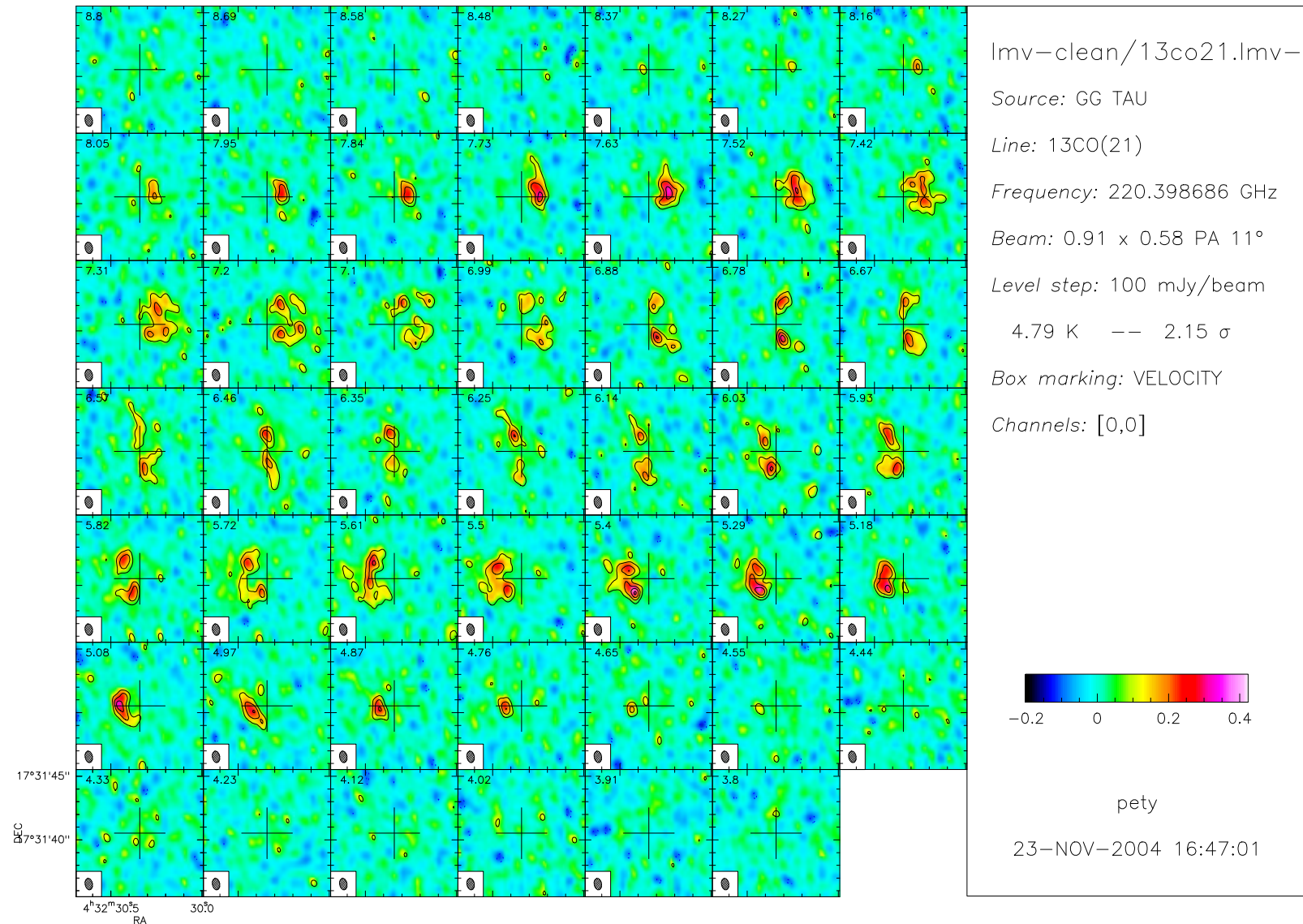
Visualization: I. G0 BIT for continuum

```
MAPPING> let name 1mm  
MAPPING> let type lmv-clean  
MAPPING> go bit  
MAPPING> input bit
```



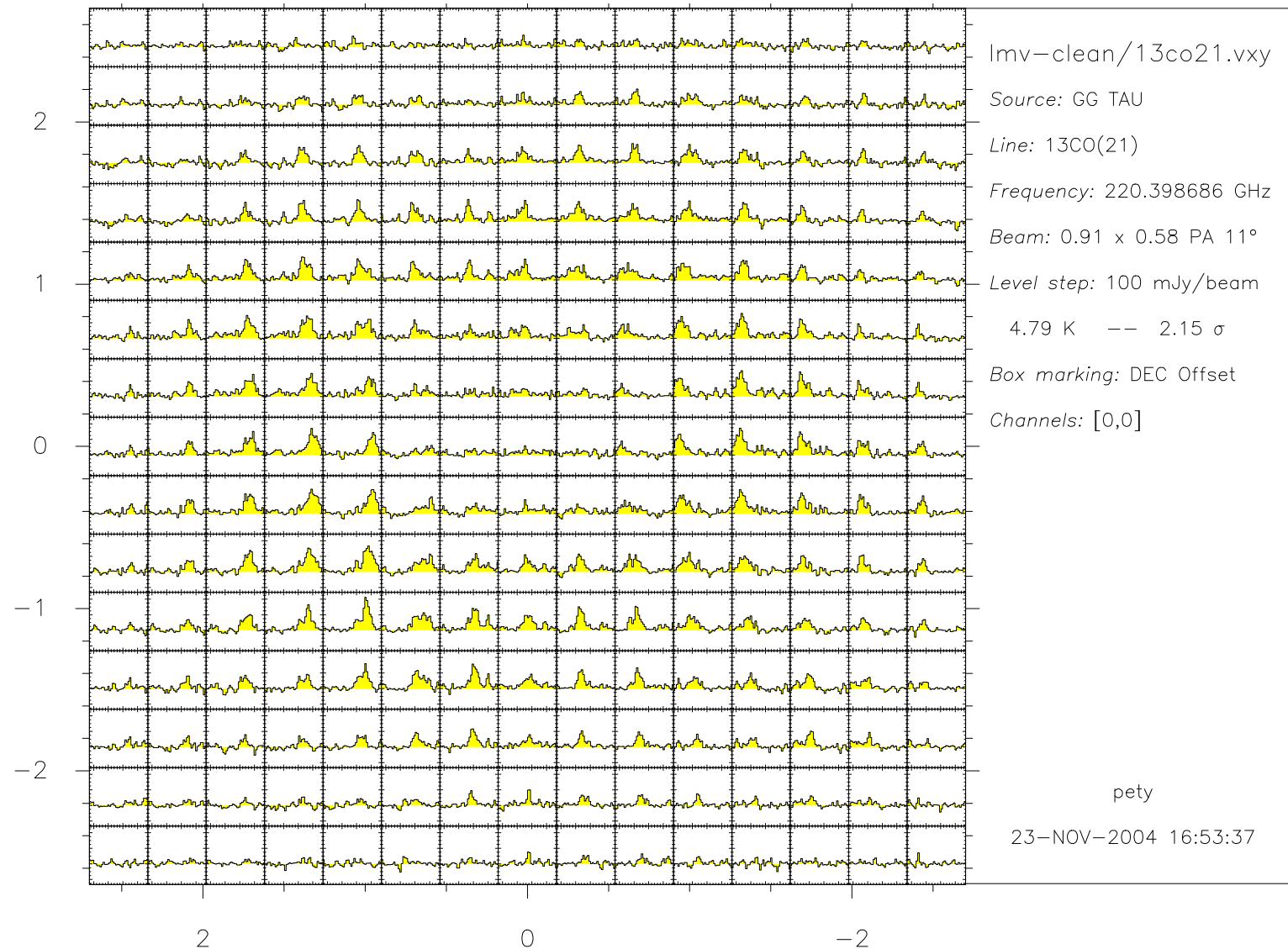
Visualization: II. GO BIT for spectra

```
MAPPING> let name 13co21  
MAPPING> let type lmv-clean  
MAPPING> go bit
```



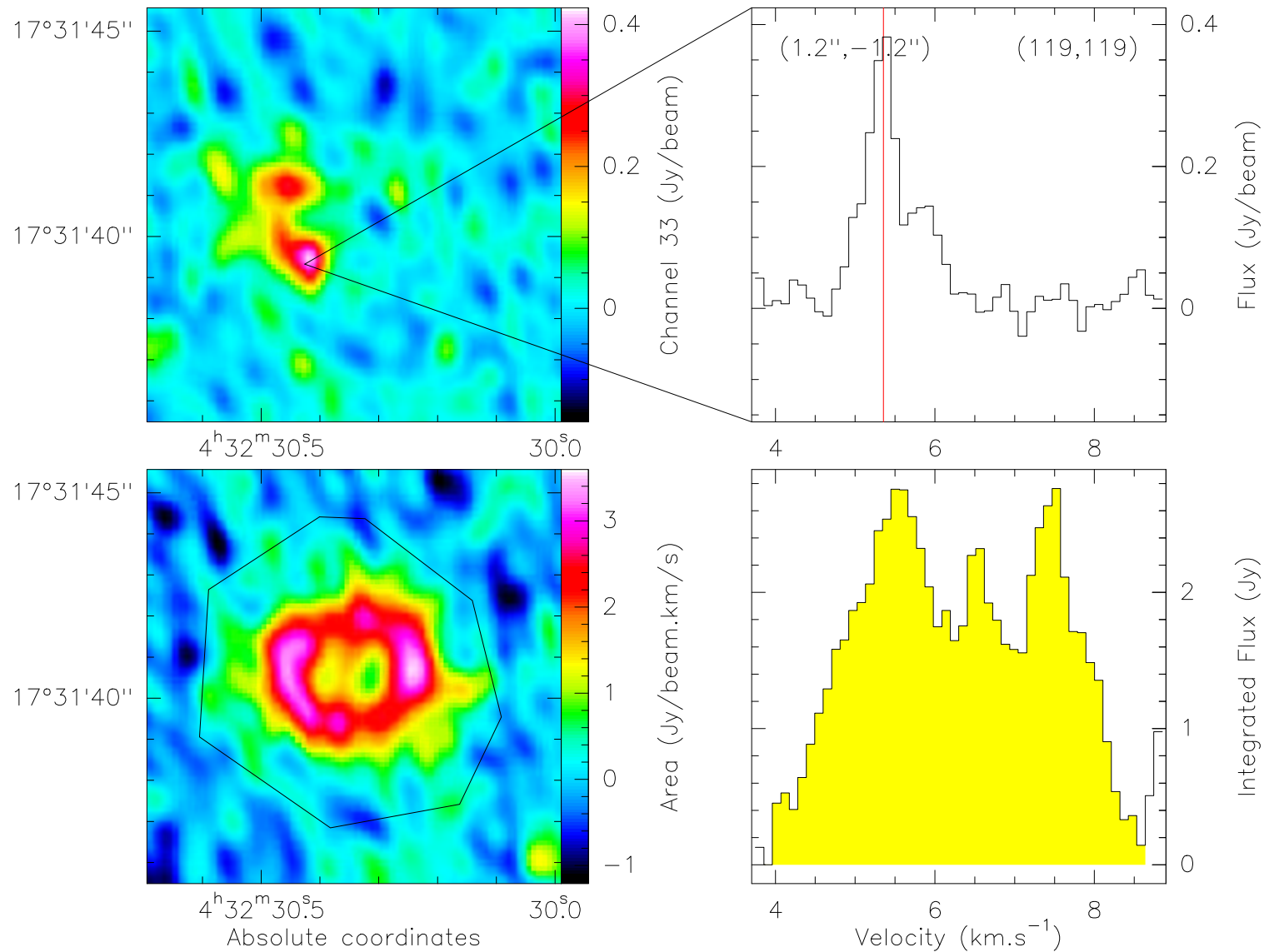
Visualization: III. GO SPECTRUM for spectra

```
MAPPING> let name 13co21  
MAPPING> let type lmv-clean  
MAPPING> go spectrum
```



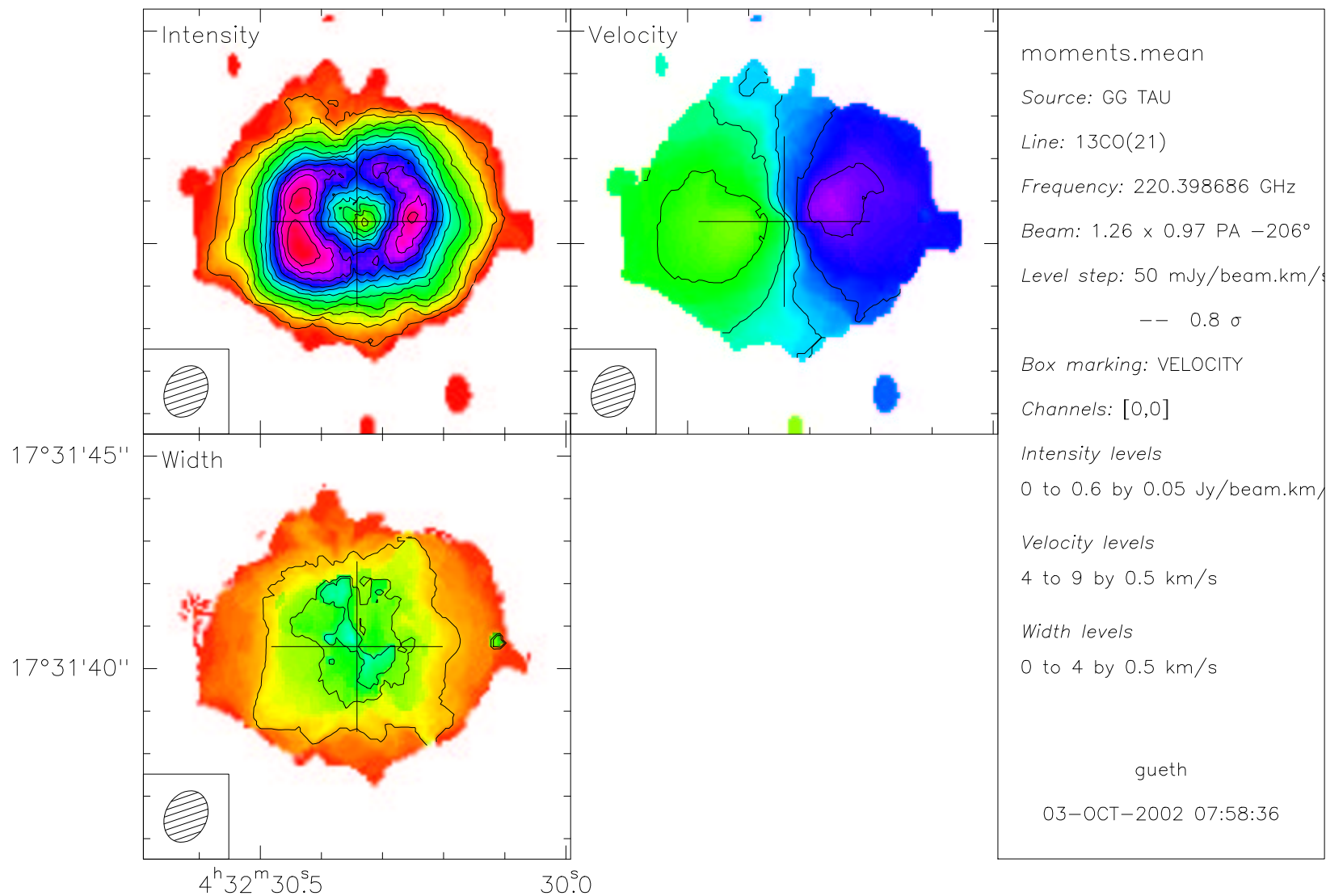
Visualization: IV. GO VIEW for spectra

```
MAPPING> let name 13co21  
MAPPING> let type lmv-clean  
MAPPING> go view
```



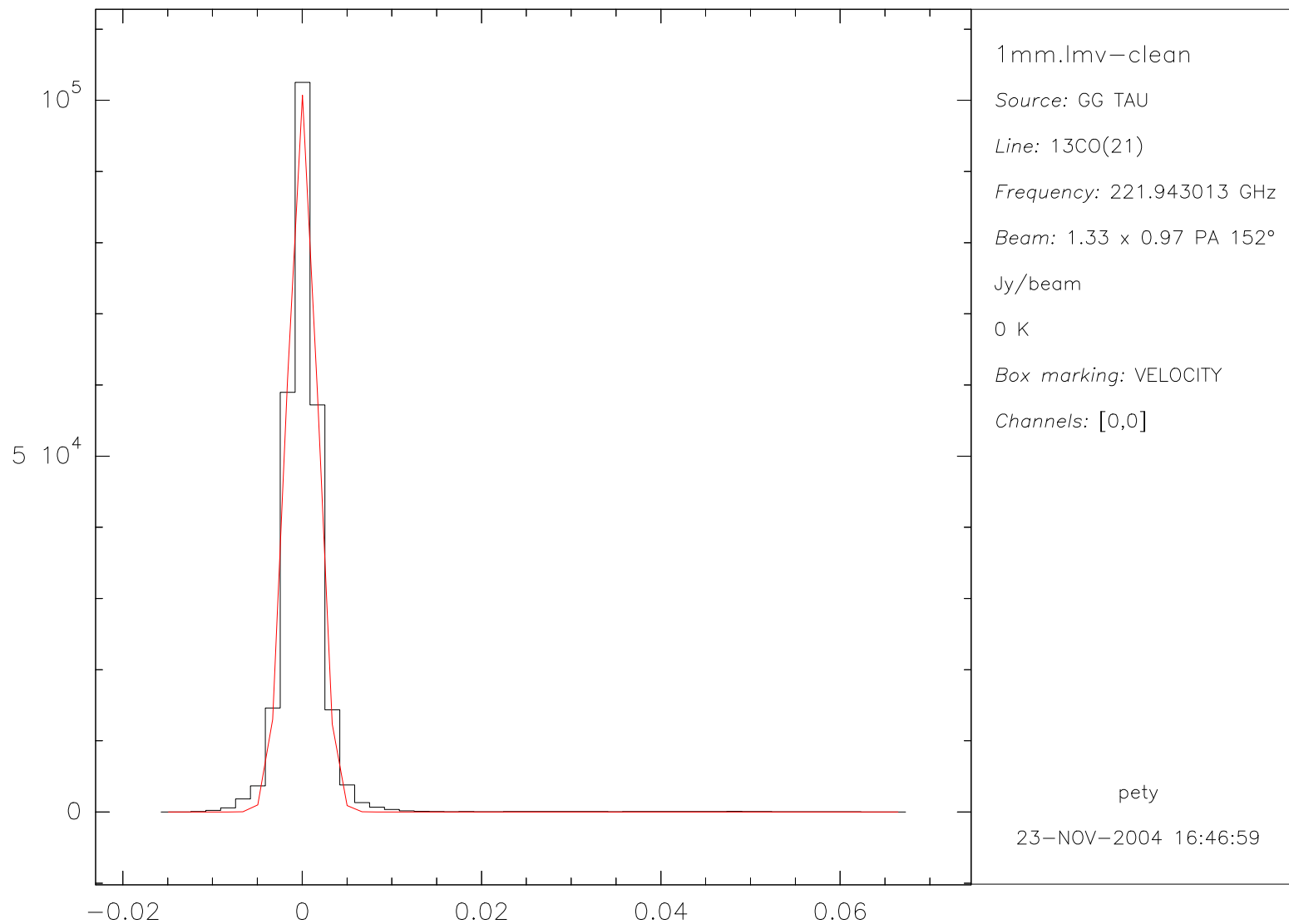
Analysis: I. Moment Estimation with GO MOMENT + GO VELOCITY

```
MAPPING> let name 13co21  
MAPPING> let type lmv-clean  
MAPPING> go moments  
MAPPING> go velocity
```



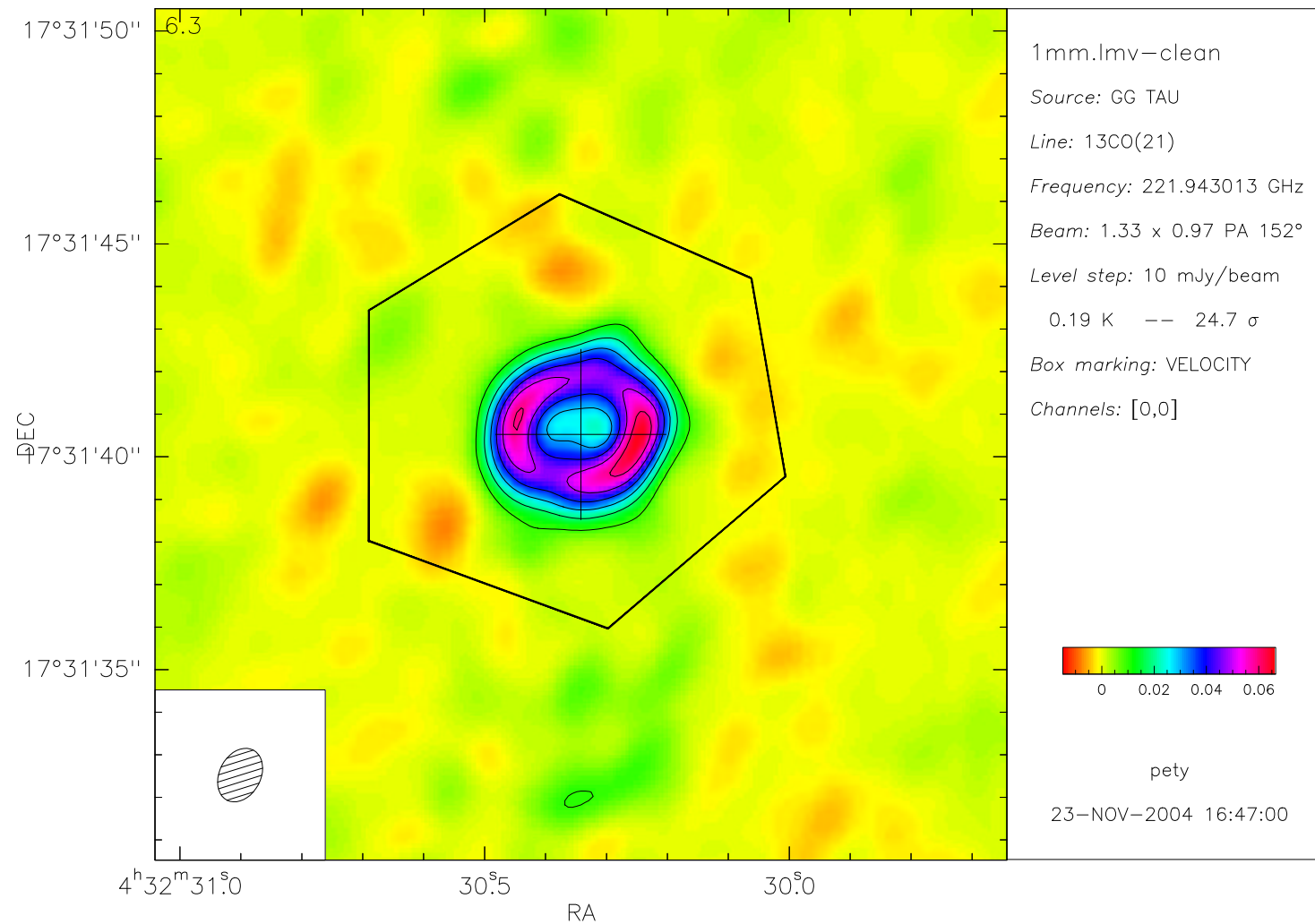
Analysis: II. Noise Estimation with GO NOISE

```
MAPPING> let name 1mm  
MAPPING> let type lmv-clean  
MAPPING> go noise  
NOISE = 1.6312926E-03 ! Real GLOBAL
```



Analysis: III. Flux Estimation with GO FLUX

```
MAPPING> let name 1mm  
MAPPING> let type lmv-clean  
MAPPING> go bit  
MAPPING> go flux  
Total Flux 461 mJy
```



Photometry: I Generalities

- Brightness = Intensity (e.g. $\text{Power} = I_\nu(\alpha, \beta) dA d\Omega d\nu$)
- Flux unit: $1 \text{ Jy} = 10^{-26} \text{ W m}^{-2} \text{ Hz}^{-1}$.
- Source flux measured by a single-dish antenna:
 $F_\nu = B * I_\nu$ with B the antenna beam.
- Relationship between measured flux and temperature scales:
 $T_A = \frac{\lambda^2}{2k\Omega_A} F_\nu$, $T_A^* = \frac{\lambda^2}{2k\Omega_{2\pi}} F_\nu$ and $T_{mb} = \frac{\lambda^2}{2k\Omega_{mb}} F_\nu$ because
 - $P_\nu = \frac{1}{2} A_e F_\nu$ Power detected by the single-dish antenna.
 - $P'_\nu = kT$ Power emitted by a resistor at temperature T .
 - $P_\nu = P'_\nu \Rightarrow T_A = \frac{A_e}{2k} F_\nu$.
 - $\lambda^2 = A_e \Omega_A$ (diffraction).
 - $\Omega_{2\pi} = F_{\text{eff}} \Omega_A$ or $F_{\text{eff}} = \frac{\text{Forward beam}}{\text{Total beam}}$.
 - $\Omega_{mb} = B_{\text{eff}} \Omega_A$ or $B_{\text{eff}} = \frac{\text{Main beam}}{\text{Total beam}}$.

Photometry: II Visibilities

Visibility unit: **Jy** because:

$$\begin{aligned} V &= 2D \text{ FT } \{ B_{\text{primary}} \cdot I_{\text{source}} \} \\ &= \iint B_{\text{primary}}(\sigma) \cdot I_{\text{source}}(\sigma) \exp(-i2\pi \mathbf{b} \cdot \sigma / c) d\Omega. \end{aligned}$$

Effect of flux calibration errors on your image:

- Multiplicative factor if uniform in uv plane.
- Convolution (*i.e.* distortion) else.

Photometry: III Dirty map

III—defined because:

- $S(u = 0, v = 0) = 0 \Rightarrow$ Area of the dirty beam is 0!
- $V(u = 0, v = 0) = 0 \Rightarrow$ Total flux of the dirty image is 0!
 \Rightarrow A source of constant intensity will be fully filtered out.
- A single point source of 1 Jy appears with peak intensity of 1.
- Several close-by point sources of 1 Jy appears with peak intensities different of 1.

Photometry: IV Clean map

(my dream: Don't take it seriously)

$I_{\text{clean}} = \frac{1}{\Omega_{\text{clean}}} (B_{\text{clean}} * I_{\text{point}})$: *i.e.* convolution of a set of point sources (mimicking the sky intensity distribution) by the clean beam.

Behavior: Brightness, *i.e.* Source flux measured in a given solid angle (*i.e.* clean beam).

Unit: Jy/sr

Consequences:

- Source flux computation by integration inside a support:

$$\text{Flux} = \sum_{ij \in \mathcal{S}} I_{\text{clean}} d\Omega$$

[Jy] [Jy/sr] [sr]

with $d\Omega$ the image pixel surface.

- From Brightness to temperature: $T_{\text{clean}} = \frac{\lambda^2}{2k} I_{\text{clean}}$

Photometry: IV Clean map (reality)

$I_{\text{clean}} = B_{\text{clean}} * I_{\text{point}}$: *i.e.* convolution of a set of point sources (mimicking the sky intensity distribution) by the clean beam.

Behavior: Brightness, *i.e.* Source flux measured in a given solid angle (*i.e.* clean beam).

Unit: Jy/beam with 1 beam = Ω_{clean} sr.

Consequences:

- Source flux computation by integration inside a support:

$$\begin{array}{ccccc} \text{Flux} = & \sum_{ij \in \mathcal{S}} & I_{\text{clean}} & \cdot & \frac{d\Omega}{\Omega_{\text{clean}}} \\ & & [\text{Jy}] & & [\text{Jy/beam}] [\text{beam}] \end{array}$$

with $\frac{d\Omega}{\Omega_{\text{clean}}}$ the nb of beams in the surface of an image pixel.

- From Brightness to temperature: $T_{\text{clean}} = \frac{\lambda^2}{2k\Omega_{\text{clean}}} I_{\text{clean}}$

Photometry: IV Clean map

Consequences of a **Gaussian** clean beam shape:

- No error beams, no secondary beams.
- T_{clean} is a main beam temperature.

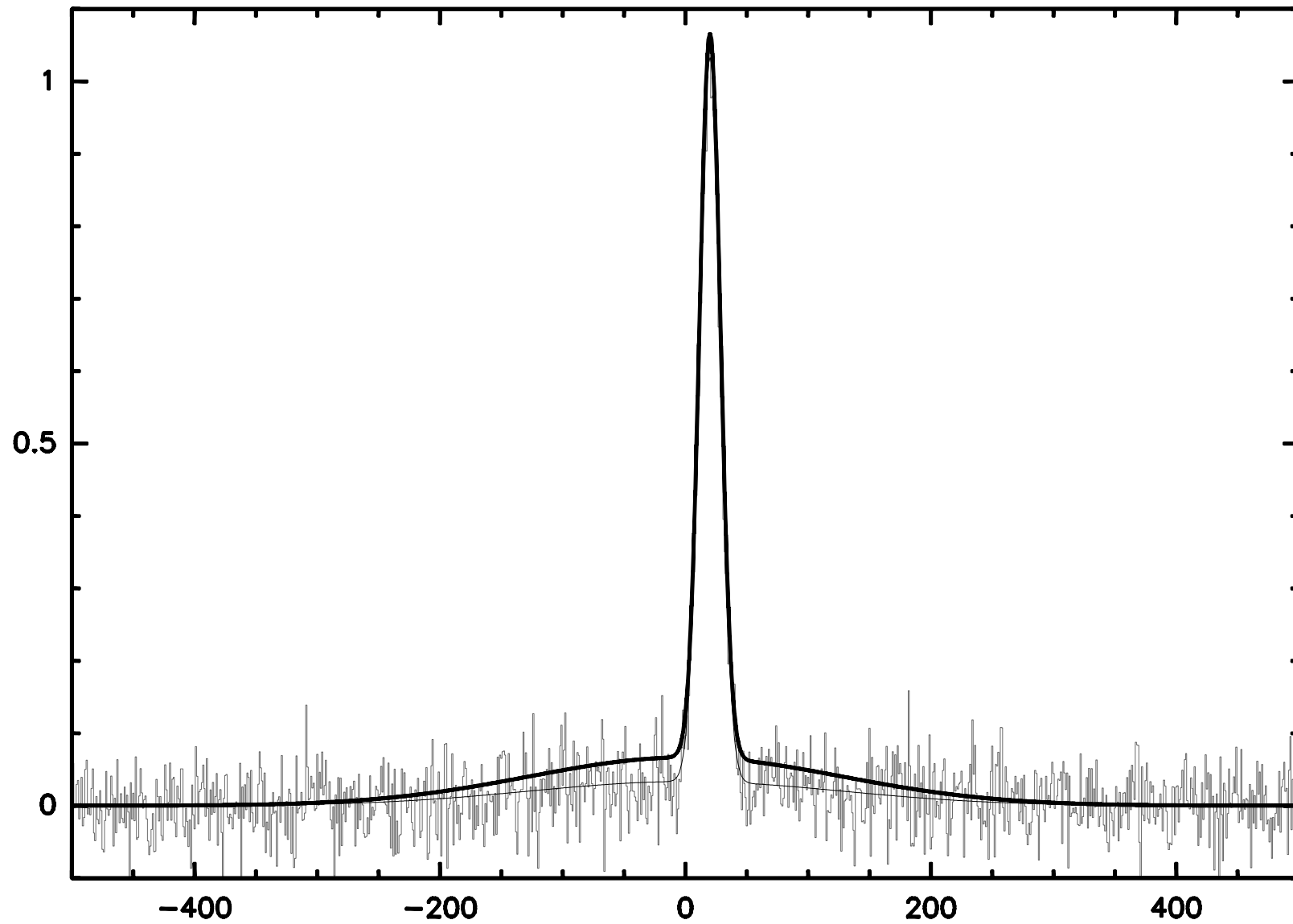
Natural choice of clean beam size: Synthesized beam size
(i.e. fit of the central peak of the dirty beam).

⇒ Minimize unit problems when adding the dirty map residuals.

Caveats of flux measurements:

- **CLEAN does not conserve flux**
(i.e. CLEAN extrapolates unmeasured short spacings).
- **Large scales are filtered out** (source size $> 1/3$ primary beam size ⇒ need of short spacings, cf. lecture by F. Gueth).
- $I_{\text{clean}} = B_{\text{primary}} \cdot I_{\text{source}} + N$
⇒ **Primary beam correction** may be needed:
$$I_{\text{clean}}/B_{\text{primary}} = I_{\text{source}} + N/B_{\text{primary}} \Rightarrow \text{Varying noise!}$$
- **Seeing scatters flux.**

Photometry: V Importance of Extended, Low Level Intensity



Writing the Paper: Your job!

J.Pety's 2nd life: GILDAS manager

Web page: <http://www.iram.fr/IRAMFR/GILDAS>

Mail to: gildas@iram.fr

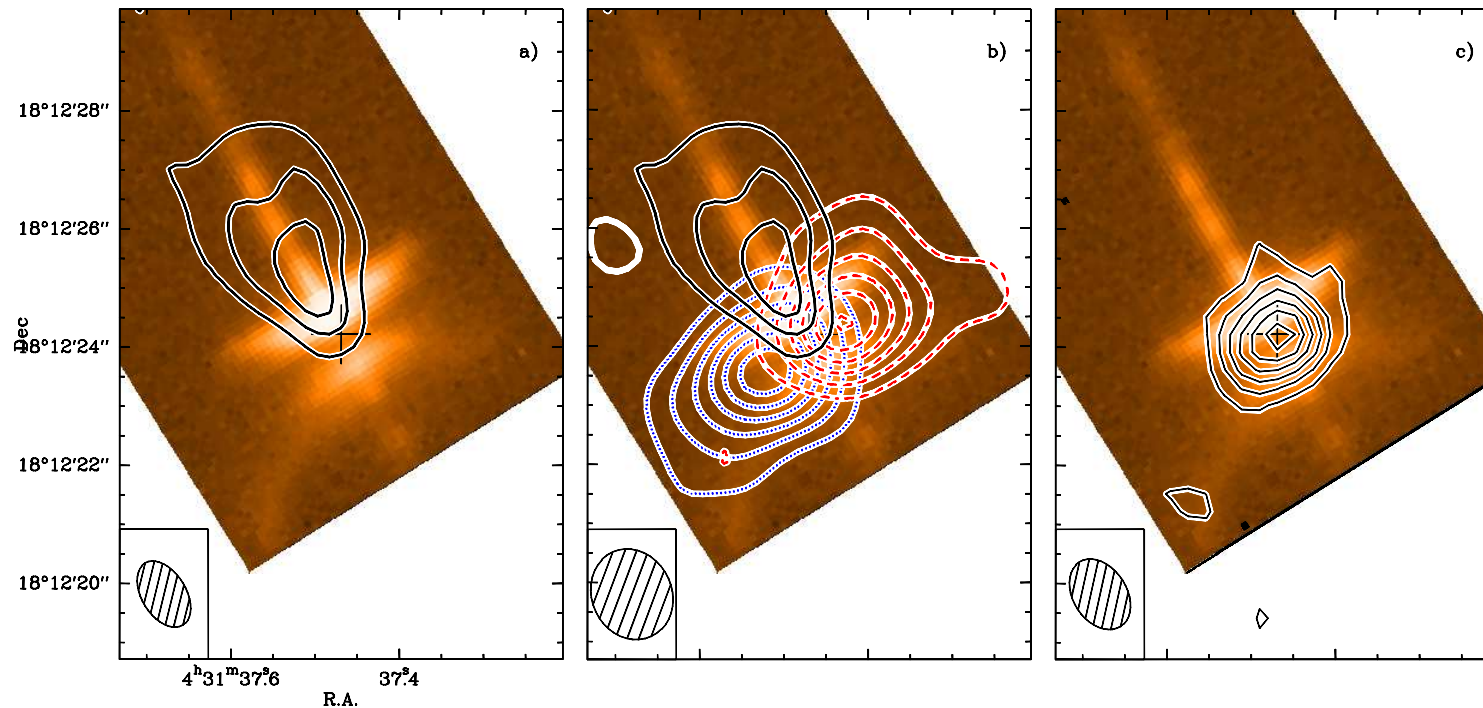


J.Pety's 3rd life: Radioastronomer

For example:

HH 30: A case study for the disk-jet-outflow paradigm.

Pety et al, 2006, A&A, in press, astro-ph/0608218



Mathematical Properties of Fourier Transform

- 1 Fourier Transform of a product of two functions
= convolution of the Fourier Transform of the functions:

$$\text{If } (F_1 \xLeftrightarrow{\text{FT}} \tilde{F}_1 \text{ and } F_2 \xLeftrightarrow{\text{FT}} \tilde{F}_2), \text{ then } F_1 \cdot F_2 \xLeftrightarrow{\text{FT}} \tilde{F}_1 * \tilde{F}_2.$$

- 2 Sampling size $\xLeftrightarrow{\text{FT}}$ Image size.

- 3 Bandwidth size $\xLeftrightarrow{\text{FT}}$ Pixel size.

- 4 Finite support $\xLeftrightarrow{\text{FT}}$ Infinite support.

- 5 Fourier transform evaluated at zero spacial frequency
= Integral of your function.

$$V(u=0, v=0) \xLeftrightarrow{\text{FT}} \sum_{ij \in \text{image}} I_{ij}.$$

Photographic Credits and References

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