

Evaluating Fog Detection Using Himawari-8 Satellite Imagery and Bispectral Image Processing

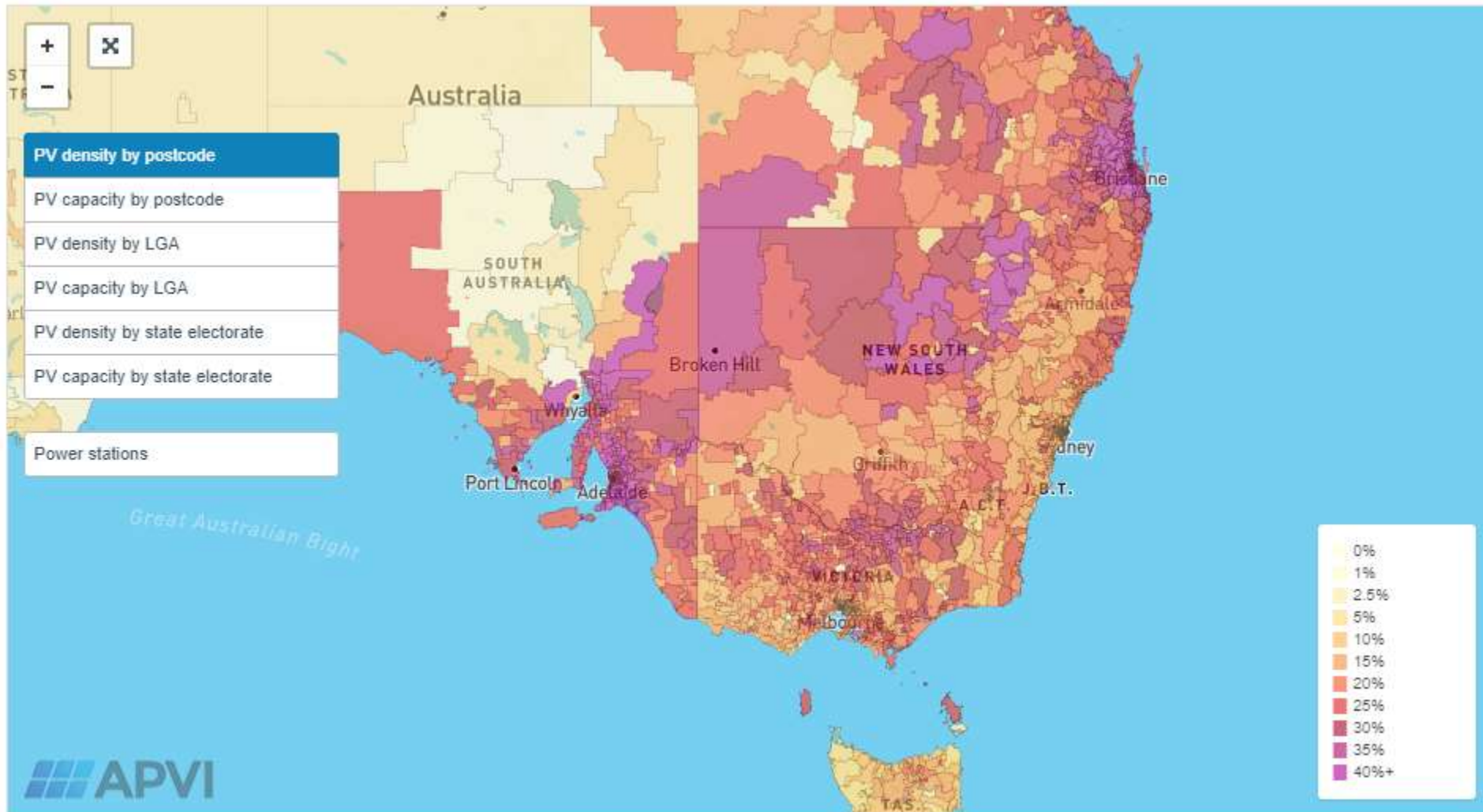
Harrison I. Andrews¹

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Momentum: Residential PV penetration

Very high compared to elsewhere in the world.



The Project at ANU

\$4M Project, ARENA & Industry backed [2016-2019]



Australian Government
Australian Renewable
Energy Agency

ARENA

Delivering solar PV forecasts to participating distribution network service providers (DNSPs).

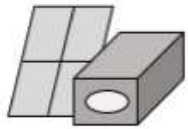
End Goal: Enable higher penetrations of solar in Australian distribution networks



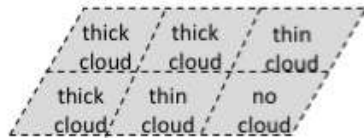
ANU Partnership with Solcast



Solar Forecasting Engine



Himawari 8 Satellite
0-6 hours
1km² at 10min



Numerical Weather Model Ensemble
6-168 hours (7 days)
30 minute

Probabilistic Radiation Forecast

PV Power Model

Inputs: Metadata & Forecast Radiation
Output: PV Power & Probability

PV Power Forecast Aggregation

Network API Service

Call: Zone/Feeder/Transformer ID
Return: Aggregated PV Power at Asset

Raw Data via DNSP Connection Agreements

Data Processing

DNSP PV Data Database
Small-scale Solar by Network Asset

Solar Metadata

DNSP Delivery

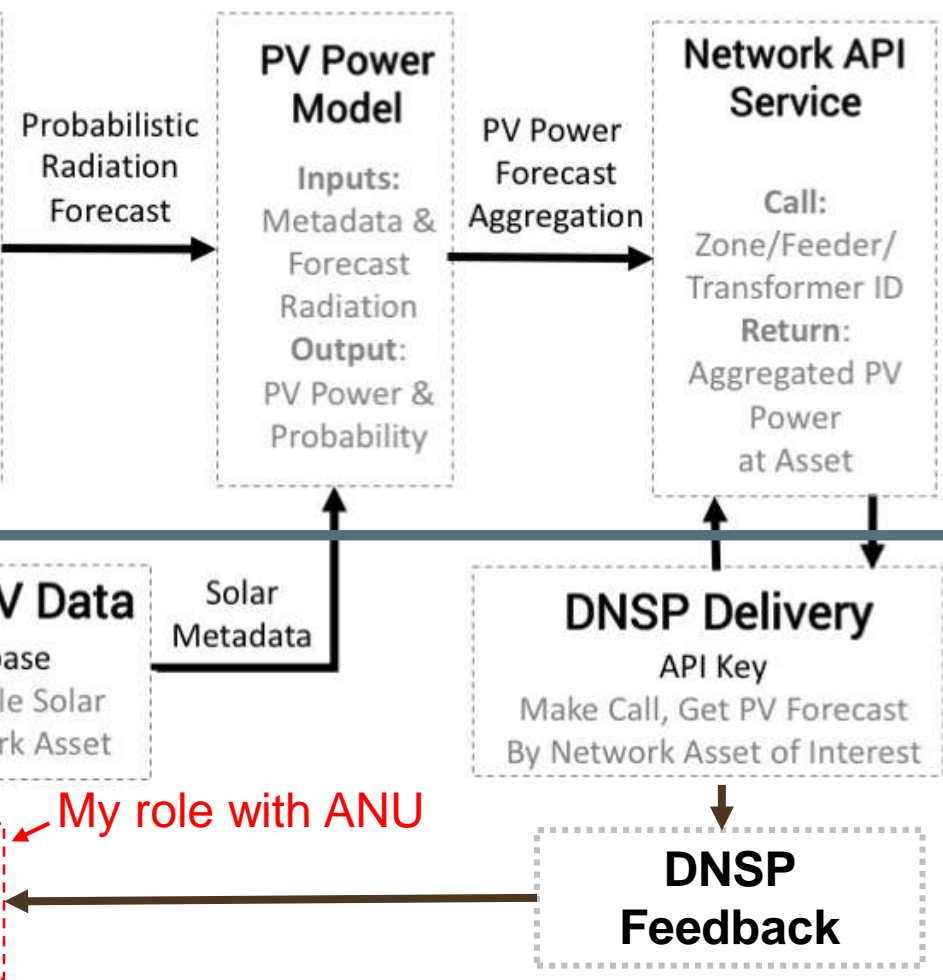
API Key
Make Call, Get PV Forecast By Network Asset of Interest

Research and Development

In depth research objectives to improve solar forecasting

My role with ANU

DNSP Feedback



Research Question

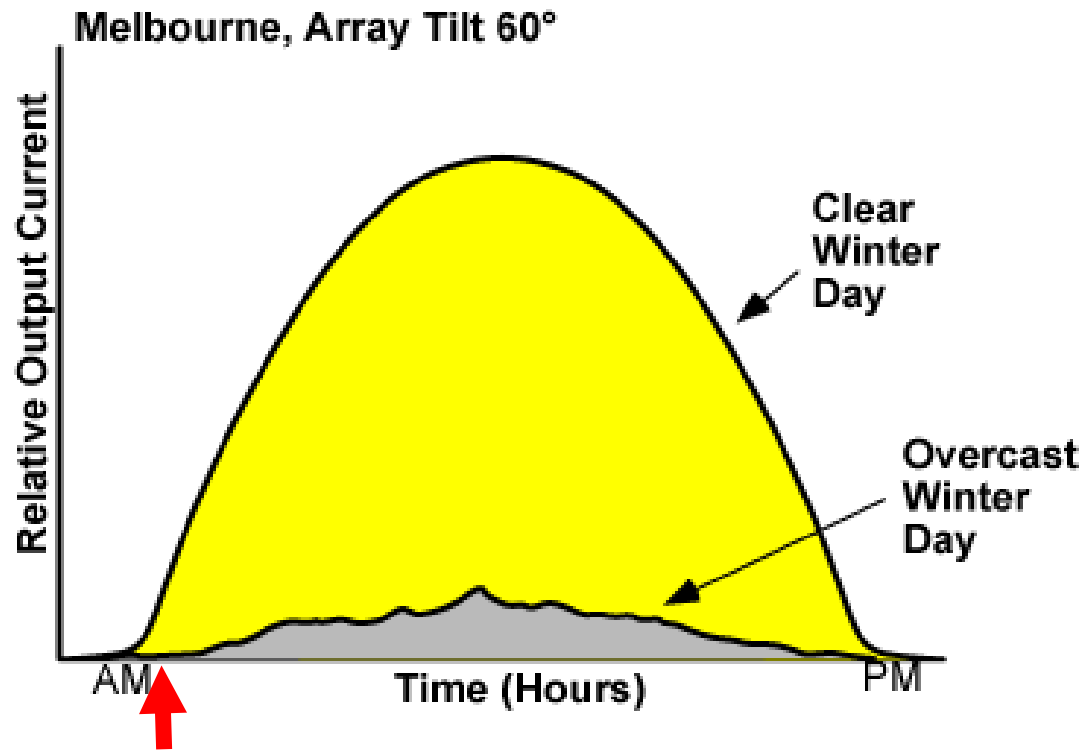
Look into whether fog events can be identified and forecasted through satellite imagery?

evoenergy

Canberra experiences more fog events than any other city in Australia

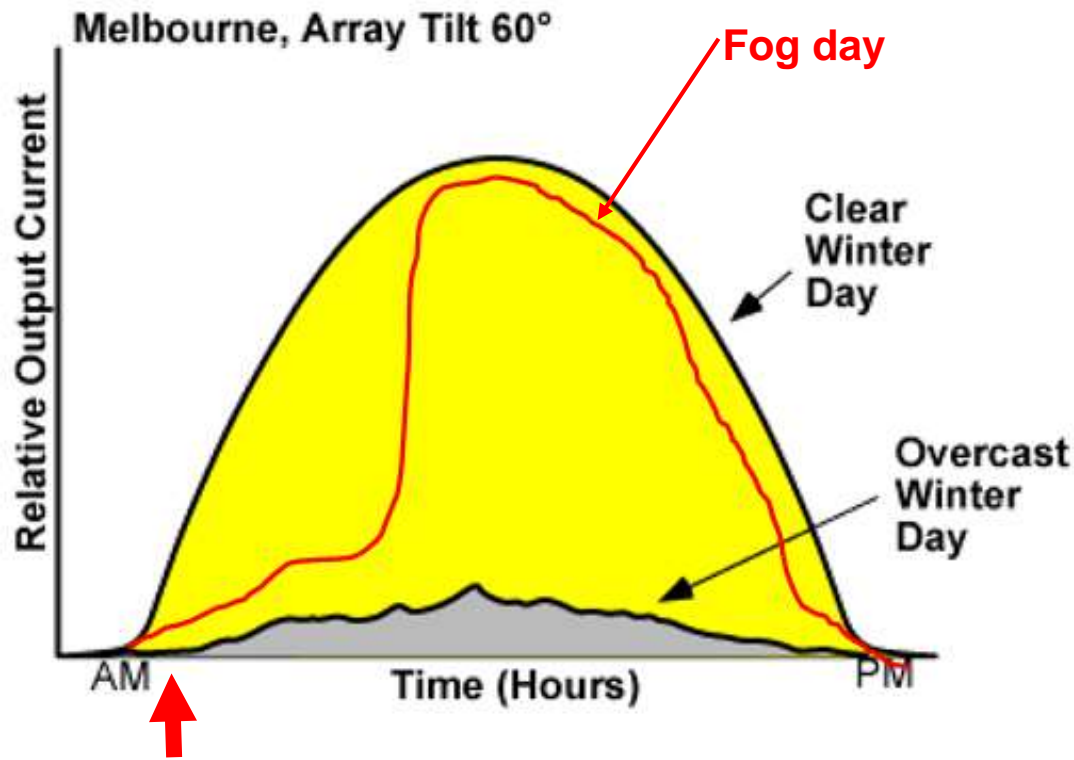


Cloud Impacts on PV



Day ahead forecast occurs here
and every 10 minutes after

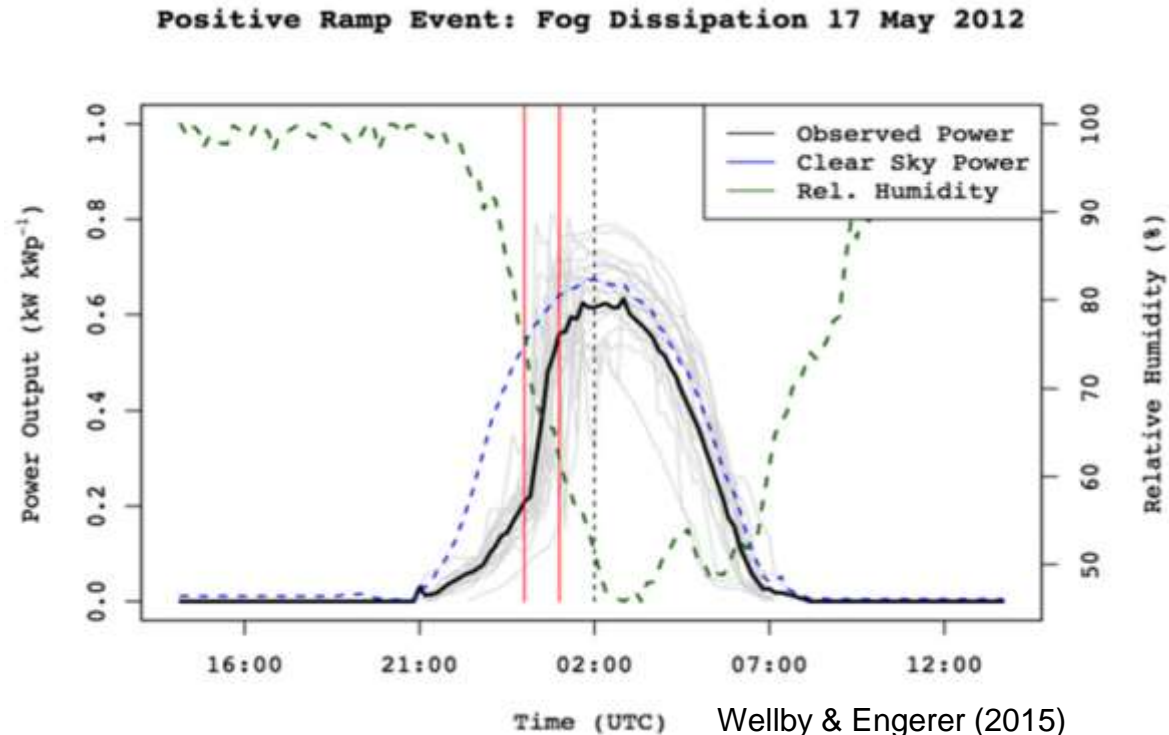
Fog Impacts on PV



Day ahead forecast occurs here and every 10 minutes after

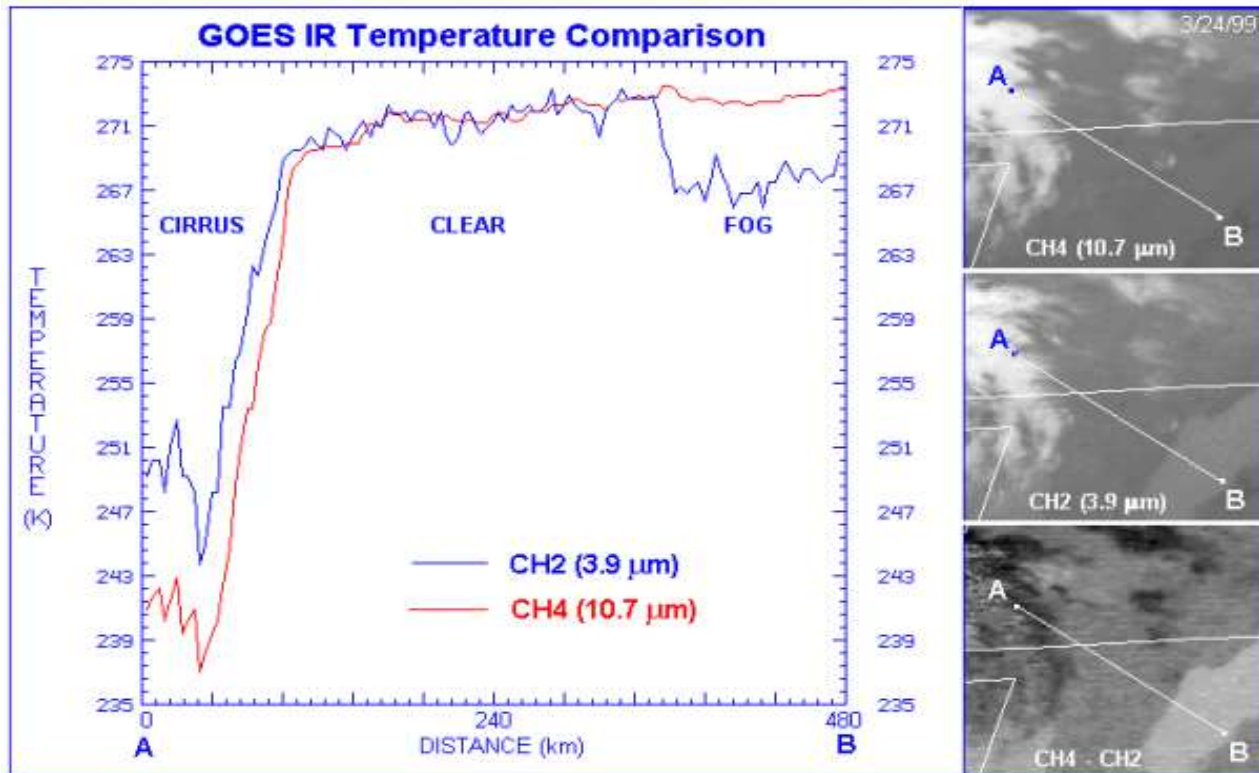
Why not just categorise as a cloud?

- Unlike most clouds, fog is static
- Fog dissipates rapidly, known to cause power ramp events
- If categorised as cloud, grid load planning, battery management and solar forecasts can be inaccurate.



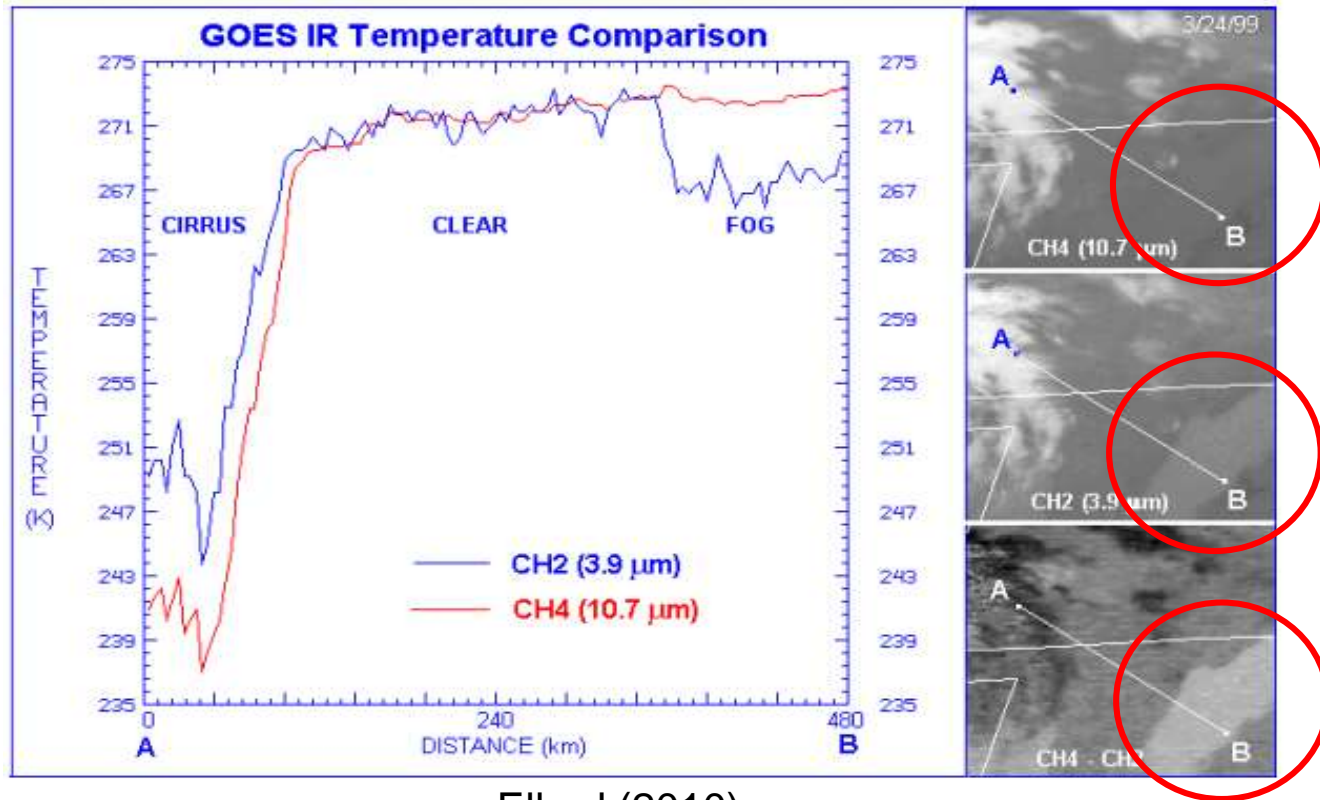


Bispectral Image Processing (BIP)



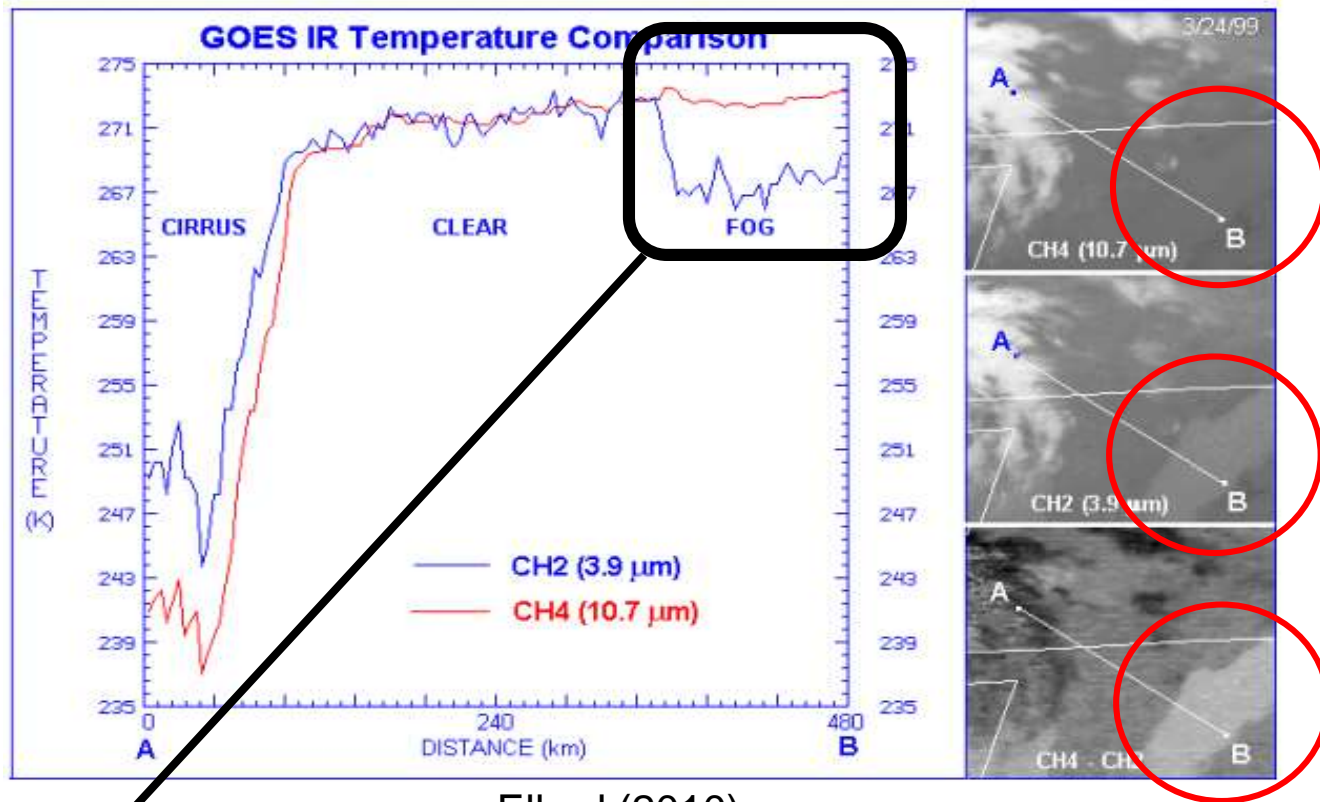
Ellrod (2010)

Bispectral Image Processing (BIP)



Ellrod (2010)

Bispectral Image Processing (BIP)



Ellrod (2010)

“small but sufficient to provide clear discrimination”

Our Methodology

Time-Step Statistic

- Mean pixel value
- Median pixel value
- 25th percentile pixel value
- Individual pixel value

Our Methodology

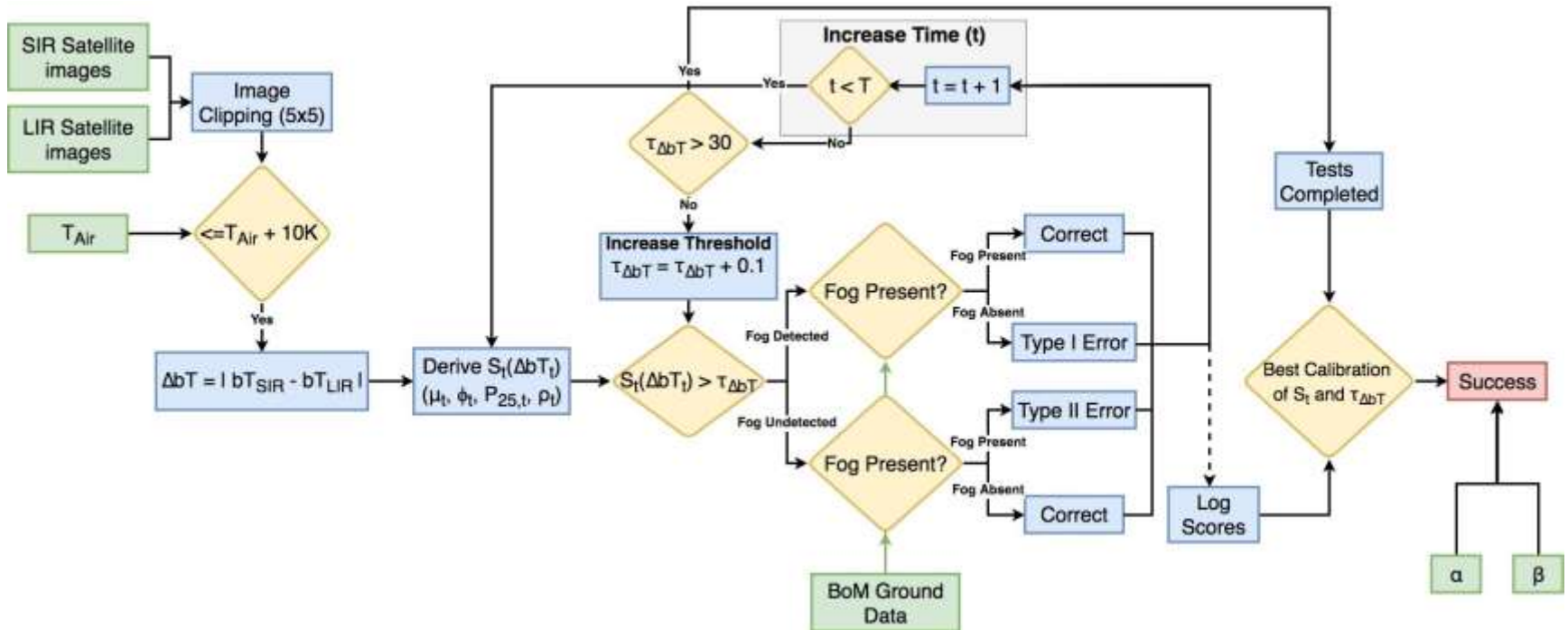
Time-Step Statistic

- Mean pixel value
- Median pixel value
- 25th percentile pixel value
- Individual pixel value

Threshold Comparison

- 0 : 0.1 : 30 K
- 301 threshold values tested

Our Methodology



Simulation Outcomes

Correct (=1)

- Fog detected & fog present
- Fog undetected & fog absent

Type I Error

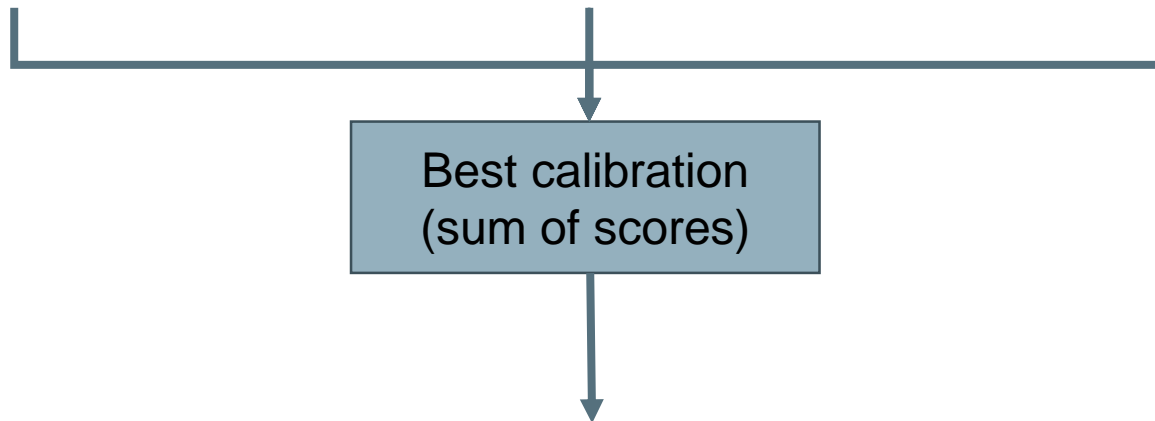
False-Positive (= -1)

- Fog detected & fog absent

Type II Error

False-Negative (= -1)

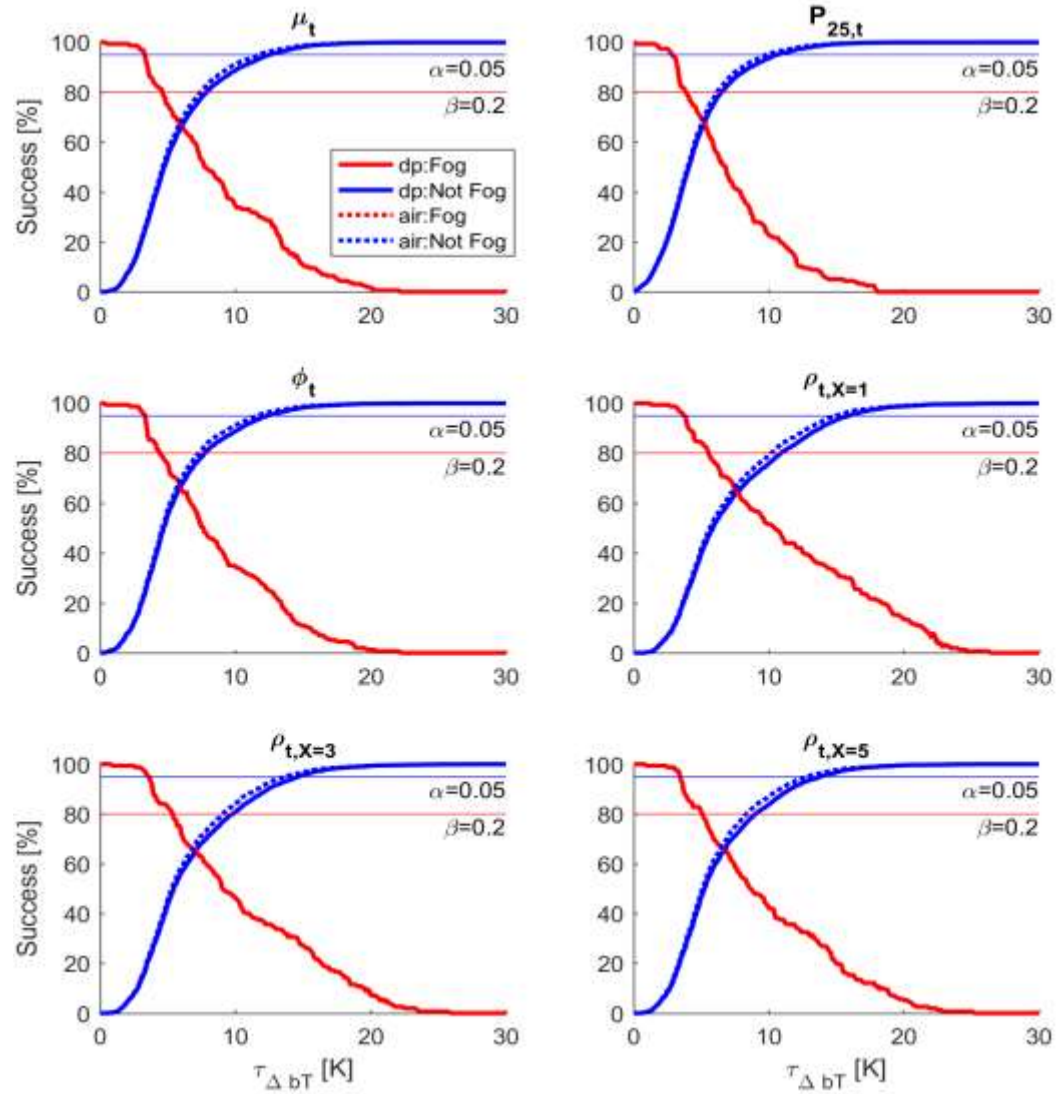
- Fog undetected & fog present



The 25th percentile with a threshold value of 5.2K gave us the best result.

?

Results



Key Findings

- The BIP method works in clear sky conditions, however the addition of a cloud detection strategy is required.
- Removal of time-steps where cloud is known to be present above recorded fog.
- Integration of cloud motion vectors could help identify cloud presence, ultimately discounting those pixels from fog analysis.
- Feedback from DNSPs: There is potential that 70% accuracy in overall detection may be sufficient for operational implementation to some extent.

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