

# IMAGER

A GILDAS software

Nov, 15th, 2022

Version 3.6-00

corresponding to code language versions:

Language	DISPLAY	1.7-00	08-Nov-2022	S.Guilloteau
Language	CLEAN	6.5-07	14-Nov-2022	S.Guilloteau
Language	CALIBRATE	1.8-02	17-Jan-2022	S.Guilloteau
Language	ADVANCED	2.6-00	08-Nov-2022	S.Guilloteau
Language	BUNDLES	1.6-02	29-Sep-2022	S.Guilloteau
Language	IMAGER	1.1-00	17-Oct-2022	S.Guilloteau

Questions? Comments? Bug reports? Mail to: [imager-hotline@services.cnrs.fr](mailto:imager-hotline@services.cnrs.fr)

The GILDAS team welcomes an acknowledgment in publications  
using GILDAS software to reduce and/or analyze data.

Please use the following reference in your publications:

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

and for **IMAGER**

<https://imager.oas.u-bordeaux.fr>

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## Notations

Throughout this document, colors are used to highlight the names of categories of entities:

- **PROGRAM** is a GILDAS program name.
- **LANGUAGE\** is a SIC Language name
- **NAME** is a command name, keyword or option
- **SICVAR** is a SIC variable
- **ScriptName** is an **IMAGER** script (external text file) that can be executed by the **@** command
- **FileName** is an external file, e.g. a data file.

Related information on **IMAGER** is available in:

- IRAM Plateau de Bure Interferometer: Introduction
- IRAM Plateau de Bure Interferometer: OBS Users Guide
- IRAM Plateau de Bure Interferometer: Atmospheric Calibration
- IRAM Plateau de Bure Interferometer: Calibration Cookbook
- CLIC: Continuum and Line Interferometric Calibration
- GREG: Graphical Possibilities
- SIC: Command Line Interpreter

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## 1 Pre-ambble

**IMAGER** is an interferometric imaging package, tailored for usage simplicity and efficiency for multi-spectral data sets.

**IMAGER is \*\*\* NOT \*\*\* MAPPING**

**IMAGER** was created because the initial infrastructure for imaging in the **MAPPING** program was not adapted to the implementation of imaging methods that became possible and/or were required for NOEMA (and useable for ALMA), such as self-calibration, wide band imaging, or routine processing of Mosaics and Short spacings.

The **IMAGER** design takes great care of efficiency, by using parallel programming and minimizing Input/Output on files. This lead to a concept with a single **READ** of data, a few (in general only 2) simple processing commands with built-in intelligent parameter guesses, a visual user control, and a single **WRITE** of the results once the user is satisfied of it.

We took the opportunity to revise and streamline the user interface, providing access to all tools through simple commands. A special effort was put on the visualization tools, which provide enhanced speed and capabilities, yet preserving a very high level of compatibility with those previously offered in **MAPPING**.

**IMAGER** was derived from **MAPPING** by S. Guilloteau. T. Jacq and E. di Folco made numerous suggestions about the user interface, and helped testing and documenting the program.

## 2 IMAGER in short

**IMAGER** is an interferometric imaging package in the GILDAS software, tailored for usage simplicity and efficiency for multi-spectral data sets.

The main goals of **IMAGER** are

1. to offer a proper implementation of imaging in case of wide relative bandwidth, where the natural angular resolution changes with frequency.
2. to implement a simple and efficient scheme to process Mosaics, including short spacings from single dish data
3. to take advantage of improved capabilities of NOEMA and ALMA, by offering new tools like self-calibration or wide bandwidth analysis.
4. to simplify user interfaces, by providing sensible defaults.
5. to minimize image sizes
6. to minimize processing time by using parallel programming as much as possible and reducing Input/Output to the strict minimum.

**IMAGER** was developed and optimized to minimize Input/Output that are the bottleneck of current computers. Therefore, **IMAGER** works mostly on internal buffers and avoids as much as possible saving data to intermediate files. File saving is done ultimately once the data analysis process is complete, which offers an optimum use of the disk bandwidth.

**IMAGER** also includes advanced display and image analysis tools, such as simple overlaying of different data cubes, etc...

## 3 IMAGER for you...

If you do not know how to do something, just use the **HOW.TO** command to express your question in a (semi-) natural way, e.g.

```
how to combine alma and aca
```

Use the **HELP** command for more details on commands. Use the **TIP** command for useful suggestions.

### 3.1 IMAGER for beginners

If you have never done any interferometry before, or if you do not know what is a *uv* table, we (**strongly**) suggest you read Sections 4.2, 5 and 6 before doing anything at all. These sections are short enough to give you the basic tools ( **HELP** plus the 5 main commands: **READ**, **UV\_MAP**, **CLEAN**, **VIEW** and **WRITE**), and will give you hints on why **IMAGER** behaves like this.

Remember two things: look at the results (command **VIEW**) at all steps, and ask more experienced users if these results make sense if any doubt arise.

### 3.2 IMAGER for previous users of MAPPING

IMAGER offers a number of advantages against MAPPING : higher speed, simpler and more consistent user interface, integrated pipeline processing, and a number of improved image analysis tools. However, the principles have not changed. Most commands remain quasi identical in IMAGER and MAPPING, with basically the same control parameters.

Actions which were driven by widgets have often been replaced by simple commands (with intuitive names). A quick look at the HELP will guide you to the commands that will do what widgets were doing before. So you can skip over the fundamentals, and focus on the new tools offered by IMAGER. In practice, for you, commands will make fairly reasonable choices of default parameters. Just do not forget to WRITE your data.

In short, the biggest changes for MAPPING users are

- the lack of use of the GO command, and thus of the NAME and TYPE variables
- the suppression of MAP\_RA MAP\_DEC MAP\_ANGLE and UV\_SHIFT which have been replaced by MAP\_CENTER
- the replacement of all tasks by simpler, standard commands.

Changing the defaults may be needed only for practical reasons:

- Optimizing computation time. This includes adjusting the field of view (variable MAP\_FIELD), resampling in velocity (command UV\_RESAMPLE) and time averaging (command UV\_TIME)
- Comparing strictly different images (on a pixel per pixel basis). Adjusting MAP\_SIZE and MAP\_CELL will become necessary in such a case.

The names of variables and most commands have been kept from MAPPING, old names appear in the HELP whenever they have been replaced.

#### 3.2.1 Forget INPUT and GO command

However, the GO command is totally obsolete. In general any GO SOMETHING is simply replaced by the equivalent command SOMETHING: e.g. type VIEW instead of GO VIEW. GO PLOT (or its variants GO BIT, GO NICE and GO MAP) and GO UVSHOW are replaced by the SHOW command, which offers many more possibilities.

The capabilities given by the INPUT MAPPING command have in general be replaced by the more flexible use of the question mark (? , or ?? , or even ???) as arguments to individual IMAGER commands. Most commands display their control parameters with such arguments.

Take a little time to browse through HELP SHOW and HELP VIEW to get familiar with IMAGER display capabilities.

### 3.3 IMAGER for huge data sets: 100 000 channel imaging with NOEMA or ALMA

For NOEMA, with the advent of PolyFiX, the paradigm has changed: a spectral window may contain a substantial number of interesting spectral lines, not just one as with the previous narrow band spectral correlator. The same can happen (although to a lesser extent) with ALMA.

That is perhaps where IMAGER is most helpful. It contains new tools to help you automating this tedious part. The primary tool is command UV\_PREVIEW which, provided one or more spectral line catalogs have been defined (see command CATALOG), allows to semi-automate the line identification among many UV tables.

The script `@ noema-scan` used after a `UV_PREVIEW` on a wide band UV table will help you identify who is who among the 64 spectral windows that PolyFix may provide.

A widget (driven by script `imager_init`) also allows simple image creation from any UV table, including continuum subtraction, referencing to different frequencies and velocities, and spectral resampling. Script `@imager-one` offers another alternative. Both can be useful examples for more advanced processing.

A much more advanced tool is the `PIPELINE` command that streamlines and even fully automates the imaging process of a whole ensemble of UV tables. See Section 13 for details.

### 3.4 IMAGER for lazy or overbooked ones

If you have many spectral lines, and need results very quickly, the `PIPELINEs` command. It can provide you one image for each spectral line specified in your line catalog that fall into the bandwidth of your data.

The default will do a pretty good job on most data sets, but can be customized for a better result. See Section 13 for details.

### 3.5 IMAGER for ALMA data

`IMAGER` implements in CASA the `casagildas()` tool that automates the transfer of calibrated visibilities from a CASA Measurement Set to UVFITS files that can be readily imaged with `IMAGER`.

### 3.6 IMAGER for image analysis and publication plots

`IMAGER` also includes general data-cube handling tools, such as spectral or spatial resampling, re-projection, image combinations, and several elaborate viewers that can be used to explore data cubes and/or prepare publications quality plots. See Sections 12

The display commands (but not the data handling tools) are also separately available in the `VIEWER` program.

## 4 IMAGER principles

### 4.1 Overview of the data reduction and analysis

Once the data has been acquired by an interferometer such as the NOEMA or ALMA, two different approaches may be used for its reduction and analysis:

- The first possibility is to clearly separate 1) the calibration, 2) the imaging and deconvolution and 3) the analysis.
- The second possibility is to merge in a single step calibration and imaging. This possibility is known as self-calibration.

While CASA uses the second paradigm, GILDAS mainly implements the first approach, as the program and the data format used for each step is different, but still allows convenient self-calibration. The basic instrumental calibration of NOEMA data is done inside `CLIC` on the NOEMA raw data format and the outcome is a *uv* table, which contains only calibrated visibilities of the astronomical source. The imaging and deconvolution are done inside `IMAGER` on the calibrated *uv* table and deliver mainly an `lmv` spectral cube (2 axes of coordinates and 1 axis

of velocity/frequency). **IMAGER** includes **VIEWER**, a superset of **GREG**, for the visualization, and provides additional image analysis functionalities, which are not specific to an interferometric use (*e.g.* they can be used with the IRAM 30 m spectral cubes as well).

The choice of clearly separating calibration and imaging+deconvolution was taken at start of the Plateau de Bure Interferometer, when the limiting number of antennas prevented the use of self-calibration. While many points of the calibration algorithms inside **CLIC** are specific to NOEMA data (in particular its range of Signal-to-Noise ratio), the algorithms of imaging+deconvolution can be used in many different contexts and the visualization and analysis of spectra cubes is mainly independent of the instrument that delivered the data. This last point implies that users can import data from ALMA (mainly through FITS format) in **IMAGER** for imaging and deconvolution, and in **VIEWER** for visualization. But the reverse is also true. While calibration of NOEMA data should be done inside **CLIC**, imaging+deconvolution and visualization+analysis can be done in other softwares (*e.g.* MIRIAD, AIPS, CASA for the imaging and deconvolution and KARMA for the visualization and analysis).

With the improvement of NOEMA (increase of the number of antennas and better receiver sensitivities) and with the advent of a new generation of interferometer (ALMA), the additional step of self-calibration may improve the consistency of the final results by imposing additional consistent constraints on the calibration. This self-calibration step is further presented in Section 9.

## 4.2 The structure of the **IMAGER** program

### 4.2.1 Structure and recommendations

The **IMAGER** program supports

- The manipulation (*e.g.* resampling), visualization and flagging of *uv* tables;
- The imaging of *uv* tables in dirty maps and beams;
- The deconvolution of dirty maps;
- The inclusion of short-spacings;
- The visualization and analysis of spectral cubes;
- The self-calibration.

It consists in a collection of commands, either dedicated to image display (the **DISPLAY** language), UV handling and imaging with deconvolution (the **CLEAN** language), implementing basic functionalities (the **SIC**, **GREG**, or **CALIBRATE** families of languages), advanced methods and image analysis tools (**ADVANCED** language) or even complex suites of operations (the **BUNDLES** language). A complete pipeline is available through the **IMAGER** language.

A few additional widgets are grouped in the **IMAGER** main menu to provide more integrated interfaces to the above possibilities, or more elaborate control. While these widgets may still evolve to offer more flexibility, the commands are in general very stable, though minor syntax adjustments may occur (usually to implement a more convenient syntax, but keeping as much as possible backward compatibility as a major constraint).



### 4.2.2 Implementation issues

The new implementation of **IMAGER** and in particular of the **UV\_MAP** and **CLEAN** commands uses most of the older code, but re-arranged such that ensembles of contiguous channels (“chunks”) are treated at once and share the same synthesized beam. Deconvolution with **CLEAN** then proceeds by using the synthesized beam with the appropriate frequency for each channel. The user can control the “chunk” size, and hence the precision of the process given the desired field of view.

As a result of the new concept, beams (whether primary or synthesized) can be 4-D arrays, as they may depend on Frequency and Field.

### 4.3 Imaging/deconvolution: a brief sequence of commands

For the user, **IMAGER** reduces the number of actions to the strict minimum. The imaging sequence is always the same:

```

1- Reading data
  READ UV MyData.uvt /RANGE Min Max Type
  ! here, optionally use UV_TIME, UV_COMPRESS, UV_BASELINE to average data
  ! or UV_FILTER, UV_CONT to filter lines or remove continuum
2- Imaging
  UV_MAP
3- Deconvolving
  CLEAN
  ! here, optionally use UV_RESTORE
4- Looking at the result
  VIEW CLEAN      ! or SHOW CLEAN
5- Writing the result
  WRITE * MyData

```

- **Step 1:** Reading the specified internal buffer (here UV) from the input file (**.uvt** file type), loading only the channels falling in the range defined by the variables Min and Max, of Type **CHANNEL**, **VELOCITY** or **FREQUENCY**. **IMAGER** recognizes whether the UV table is for a single field or a mosaic. The only difference between the single field and mosaic cases is that **IMAGER** yields a Sky brightness image for Mosaics, while the computed sky brightness of a single field is not automatically corrected for the primary beam attenuation. Imaging for multiple fields will be presented in Section 7. Single Dish data can also be loaded in the following way : **READ SINGLE File**.
- **Step 2:** Computing a dirty map and beam from a UV data. **UV\_MAP** processes single fields as well as Mosaics.
- **Step 3:** Deconvolving the **DIRTY** image map (a Single-field or Mosaic) using the dirty **BEAM** with the current **METHOD**. The default for the SIC variable **METHOD** is **HOGBOM**, the other supported methods being **CLARK**, **MRC**, **MULTI** and **SDI**. See **CLEAN ?** for the other SIC variables controlling the deconvolution process. The outputs are the **CLEAN** and **RESIDUAL** images, and the Clean Component Table **CCT**, all being stored in dedicated SIC variables.
- **Step 4:** Plotting the result in the specified internal buffer (**CLEAN**). Optionally, the user can restrict the plot to a subset of channels through the optional arguments First and Last. **SHOW CLEAN** can also be used instead, and produces a different type of plot.

- **Step 5:** Writing all modified image-like buffers (not the UV tables) under the common file name "MyData". In the case of the present example, the following files are produced: `MyData.lmv`, `MyData.lmv-clean`, `MyData.cct`, `MyData.beam`, which correspond to the buffers: `DIRTY`, `CLEAN`, `CCT`, and `BEAM`, respectively. `WRITE UV MyData` would only write the internal buffer (`UV`) in the file `MyData.uvt` (the default extension corresponds to the specified buffer data type).

#### 4.4 Getting Help: the HELP command and the ? token

As with any `SIC` based program, simple call to `HELP` will display the various languages (e.g., `SIC\`, `GREG\`, `CALIBRATE\`, `CLEAN\`) accessible to the help documentation and list some commands with available documentation. Note that `CLEAN` is a command and `CLEAN\` a language (i.e., a family of commands). The language of a given command is recalled in the help of each command.

Example: the command `APPLY` belongs to the language `CALIBRATE\`, it has one argument which can be `AMPLI` or `PHASE` exclusively, one optional argument `gain`, and one option `/FLAG`.

```
IMAGER> help apply
      [CALIBRATE\]APPLY [AMPLI|PHASE [gain]] [/FLAG]
```

In the provided description, arguments within `[]` are optional. Upper case arguments are fixed keywords that can (in general) be abbreviated. A `|` character separates the allowed keyword values. Lower-case arguments are expected to be numbers, text, filenames, `SIC` variables or expressions that can be evaluated.

A brief description of the imager program can be obtained through:

```
IMAGER> help imager
USER\IMAGER = "@ welcome.ima"
```

IMAGER is a interferometric imaging package, tailored for usage simplicity and efficiency for multi-spectral data sets.

The basic concept of IMAGER is the use of a simple  
 READ data - ACTION(s) - [SHOW or VIEW] - WRITE  
 sequence of commands, minimizing the data I/O as much as possible.  
 Automatic guesses of appropriate default values for the ACTIONS  
 parameters is implemented whenever possible.

Additional Help Available:

```
Actions      BEAM_Handlin MAP_Handling UV_Handling  WebPage
HOW_TO      MAPPING
```

In addition, finding documentation and help for the `IMAGER` commands can be done in three different ways:

- a simple call to the `HELP` command provides a description of the command and its arguments and options
- the command name followed by one or more questions marks will display some partial help on the command and its most useful parameters ("`Command ?`"), its second level parameters for advanced users ("`Command ???`"), all its parameters ("`Command ????`").

Documentation on subtopics of a given command (e.g., Variables, Arguments, or Results) can be obtained through: `HELP command subtopic`. The list of available subtopics is found at the bottom of the documentation of each command:

```
IMAGER> help uv_map
[...]
Additional Help Available:
Mosaics      /FIELDS      /RANGE      /TRUNCATE
Variables:
              BEAM_STEP    MAP_CELL    MAP_CENTER  MAP_CONVOLUT MAP_FIELD
MAP_POWER    MAP_PRECIS    MAP_ROBUST  MAP_ROUNDING MAP_SHIFT    MAP_SIZE
MAP_TAPEREXP MAP_TRUNCATE  MAP_UVTAPER MAP_UVCELL   MAP_VERSION
Old_Names:
              convolution  map_angle   map_dec     map_ra      mcol
uv_cell      uv_shift      uv_taper    taper_expo   wcol        weight_mode
```

Subtopics that appear in UpperCase in the Additional Help Available list are case insensitive. Subtopics that are in LowerCase or mixed case are strictly case sensitive.

Example: the following command will list the control variables of the `UV_MAP` function and describe the associated parameter(s):

```
IMAGER> help uv_map Variables
UV_MAP Variables:
      [CLEAN\]UV_MAP ?
      Will list all MAP_* variables controlling the UV_MAP parameters.
```

The list of control variables is (by alphabetic order, with the corresponding old names used by Mapping on the right)

New names	[ unit]	-- Description --	% Old Name
BEAM_STEP	[ ]	Channels per dirty beam	% MAP_BEAM_STEP
MAP_CELL	[ arcsec]	Image pixel size	
MAP_CENTER	[ string]	RA, Dec of map center, and Position Angle	
MAP_CONVOLUTION	[ ]	Convolution function	% CONVOLUTION
MAP_FIELD	[ arcsec]	Map field of view	
MAP_POWER	[ ]	Maximum exponent of 3 and 5 allowed in MAP_SIZE	
MAP_PRECIS	[ ]	Fraction of pixel tolerance on beam matching	
MAP_ROBUST	[ ]	Robustness factor	% UV_CELL[2]
MAP_ROUNDING	[ ]	Precision of MAP_SIZE	
MAP_SIZE	[ ]	Number of pixels	
MAP_TAPEREXP	[ ]	Taper exponent	% TAPER_EXPO
MAP_TRUNCATE	[ %]	Mosaic truncation level	
MAP_UVCELL	[ m]	UV cell size	% UV_CELL[1]
MAP_UVTAPER	[m,m,deg]	Gaussian taper	% UV_TAPER
MAP_VERSION	[ ]	Code version (0 new, -1 old)	

See `HELP UV_MAP Old_names:` for deprecated variable names.

A more detailed description (type, size) of a given variable can be obtained through `help command variable`, as in this example:

```
IMAGER> help uv_map map_uvtaper
UV_MAP MAP_UVTAPER
```

```
MAP_UVTAPER[3] Real
```

Parameters of the tapering function (Gaussian if MAP\_TAPEREXPO = 2): major axis at 1/e level [m], minor axis at 1/e level [m], and position angle [deg].

MAP\_UVTAPER is an array that requires 3 values of type Real.

The default values of the useful parameters are checked through **Command ?**<sup>1</sup>

UV\_MAP makes a dirty image and a dirty beam from the UV data

Behaviour is controlled by a number of SIC Variables

- BEAM\_STEP and MAP\_PRECIS control the dirty beam precision
- MAP\_CENTER controls shifting and rotation
- MAP\_CELL[2], MAP\_SIZE[2], MAP\_FIELD[2] control the map sampling
- MAP\_UVTAPER[3], MAP\_UVCELL and MAP\_ROBUST control the beam shape and weighting scheme

---- Basic parameters		Selected	Recommended
Map Size (pixels)	MAP_SIZE	[ 0 0 ]	[ 0 0 ]
Field of view (arcsec)	MAP_FIELD	[ 0 0 ]	[ 0 0 ]
Pixel size (arcsec)	MAP_CELL	[ 0 0 ]	[ 0 0 ]
Map center	MAP_CENTER	[ ]	
Robust weighting parameter	MAP_ROBUST	[ 0 ]	
UV cell size (meter)	MAP_UVCELL	[ 0 ]	[ 0 ]
UV Taper (m,m,)	MAP_UVTAPER	[ 0 0 0 ]	

For commands that support the **?** mechanism, **Command ? ControlVariable** and, in most cases, **Command ControlVariable ?** are shortcuts to **HELP Command ControlVariable**.

#### 4.5 IMAGER versus CASA: controlling the number of synthesized beams, BEAM\_STEP

In aperture synthesis, the angular resolution scales with the frequency: in fact the whole Fourier plane scales with this frequency, so that the angular scaled defined by the baselines varies across the frequency coverage. Accordingly, when using sufficiently wide bandwidths (and/or imaging sufficiently large areas), it becomes important to account correctly for this effect.

The CASA and **IMAGER** approaches to this problem differ. CASA systematically produces one synthesized beam per spectral channel, leading to a frequency variable spatial resolution. In this approach, CASA can handle different weighting for individual channels, optimizing signal to noise, but the interpretation of the data becomes more difficult since there is no unique angular resolution after deconvolution.

The approach offered by **IMAGER** is different, and can be controlled by variable **BEAM\_STEP**.

---

<sup>1</sup>For users familiar with **MAPPING**, the question mark replaces the capabilities of the **INPUT Command** although the output format may be slightly different.

- `BEAM_STEP` = 0 instructs `IMAGER` to produce a single synthesized beam for all channels. This is appropriate for narrow bands and spectral channels with very similar noise (ideally identical). Unavoidably, the synthesized beam is only an approximation, exact only at the reference frequency.
- `BEAM_STEP` = N instructs `IMAGER` to ensure that N consecutive channels share the same synthesized beam. This can be used when channels have the same weights (same effective UV coverage) but the overall bandwidth is large.
- `BEAM_STEP` = -1 instructs `IMAGER` to derive the number N of consecutive channels that can share the same beam to within a certain precision in the imaged field of view. This precision is given by `MAP_PRECIS`. The derived N will depend on this number, on the relative bandwidth and on the size of the synthesized field (hence `MAP_FIELD` or `MAP_CELL`  $\times$  `MAP_SIZE`).
- `BEAM_STEP` = 1 mimicks to some extent the behaviour of CASA.

However, contrary to CASA, `IMAGER` can use a common clean beam in all cases. This is achieved through the use of the so-called **JvM** factor, which approximately scales the undeconvolved residuals to match the flux scale of the Clean components. This behaviour is only obtained through the `UV_RESTORE` command.

`BEAM_STEP` is a key control parameter for `IMAGER`. The `IMAGER` pipelines (see Section 13) use sensible defaults for each telescope, but users should be aware of this possible difference when comparing with CASA results.

## 5 The input data: UV Tables

The main goal of **IMAGER** is to convert interferometric measurements stored in *uv* tables into images suitable for astrophysical interpretation. *uv* tables contain a set of visibilities. *uv* tables being the starting point, **IMAGER** contains a number of commands to read then and handle them.

### 5.1 In a nutshell

For NOEMA, create with **CLIC** a UV table from the current index of cross-correlation observations and selected spectral window, and read it with **IMAGER**

```
$ clic
CLIC> (FILE ; FIND ; SET )    ! Build your index and spectral Window selection
CLIC> TABLE MyTable.uvt [NEW] [/MOAIC]    ! Create a UV table
CLIC> EXIT
$ imager
IMAGER> READ MyTable.uvt [/Options ]
```

A complete set of UV tables for all spectral windows and all sources can be automatically created from an ensemble of *.hpb* data files by

```
$ clic
CLIC> @ all-tables
CLIC> EXIT
$ imager
IMAGER> SIC FIND *.uvt
IMAGER> READ UV 'dir%file[1]'    ! For the first one...
```

For ALMA, create with **CASA** a list of UVFITS files from a Measurement Set, convert them with **IMAGER**

```
$ casa
CASA <2>: vis='MyMeasurementSet.ms'
CASA <3>: casagildas()
CASA <4>: casagildas("Do")
CASA <5>: exit()
$ imager
IMAGER> sic find *.uvfits
IMAGER> for string /in dir%file
IMAGER:   @ fits_to_uvt 'string'
IMAGER: next
```

or, even simpler, by using the **PIPELINE** command.

```
$ imager
IMAGER> PIPELINE ORGANIZE
```

Conventions for file naming are described in Section 5.4. Each *uv* table can later be read separately.

## 5.2 UV table description

### 5.2.1 UV table data format

A *uv* table is a specific 2-D Gildas table, with a few additional informations in the header, and a special interpretation of the data organisation.

In a standard *uv* table, each *line* describes a visibility. Here a *line* designate either the first or second axis of the table, and a *column* the other one. *uv* tables may appear in both orders. The default one is *line* on 1st axis (`.uvt` ordering, used by most application). The `.tuv` ordering obtained by a 21 transposition is used essentially for display, as in this case the *column* has the same meaning as for the **COLUMN** of **GREG**.

The number of lines of a *uv* table is thus the number of visibilities described in the table. Each *column* of the table stores a particular property of the visibilities, namely:

**Column 1** U in meters;

**Column 2** V in meters;

**Column 3** W in meters or Scan number;

**Column 4** Observation date (integer **CLASS/CLIC** Day Number<sup>2</sup>);

**Column 5** Time in seconds since 0:00 UT of above date;

**Column 6** Number of the first antenna used to measure the visibility;

**Column 7** Number of the second antenna used to measure the visibility;

**Column 8** Real part for the first frequency channel;

**Column 9** Imaginary part for the first frequency channel;

**Column 10** Weight for the first frequency channel;

**Columns 11-13** Same as column 8-10 but for the second frequency channel, or for the second Stokes parameter of this channel.

... etc... for all channels

**Columns N-ntrail+1 ... N** Trailing columns after the channel visibilities.

If a *uv* table describes **nvis** visibility spectra composed of **nchan** frequency channels, each with **nstokes** Stokes parameters, the size of the table will thus be: **nvis** lines of **7+3\*nchan\*nstokes+ntrail** columns, where **ntrail** is the number of trailing columns.

### 5.2.2 *uv* header

A *uv* table header contains all the informations of a GDF header but some of these informations have a special meaning in this context. Command **HEADER** is the standard way inside GILDAS to display in a human readable way the header of GDF file. For instance, the command  
**IMAGER> header gag\_demo:demo-line.uvt**  
 would display

---

<sup>2</sup>The **CLASS/CLIC** is a "radio Julian date" (or "Jansky Julian date"), which starts as  $-2^{15}$  on the date of the first radio observation by Karl Jansky. It is thus the Modified Julian date minus 60549. That choice was made to maximize the time interval over which radio astronomical data could be usefully stored in an **integer\*2**, back when 2 bytes of header space per spectrum were a significant consideration. This date has little meaning outside the rather sparse community of souls gathered around the **CLASS** and **CLIC** programs, however...

```

1  W-GDF, UNKNOWN Velocity type defaulted to LSR
2  File : /Users/guilloteau/gildas/gildas-exe-dev/demo/demo-line.uvt  REAL*4
3  Size      Reference Pixel      Value      Increment
4      103    16.000000000000000    220398.688000000    -0.183792725205421
5      9146   0.000000000000000    0.000000000000000    1.000000000000000
6  Blanking value and tolerance    1.23455997E+34    0.00000000
7  Source name      GG_TAU
8  Map unit         Jy
9  Axis type        UV-DATA      RANDOM
10 Coordinate system EQUATORIAL    Velocity    LSR
11 Right Ascension  04:32:30.34200  Declination 17:31:40.5230
12 Lii      0.000000000000000    Bii      0.000000000000000
13 Equinox      2000.0000
14 Projection type AZIMUTHAL      Angle      0.000000000000000
15 Axis 0      A0      04:32:30.34200  Axis 0      D0      17:31:40.5230
16 Baselines      0.0      0.0
17 Axis 1 Line Name 13C0(21)      Rest Frequency 220398.68800000000
18 Resolution in Velocity 0.25000000    in Frequency  -0.18379273
19 Offset in Velocity 6.3000002    Doppler Velocity -40.755900
20 Beam      0.00      0.00      0.00
21 NO Noise level
22 NO Proper motion
23 NO Telescope section
24 UV Data Channels: 32, Stokes: 1 None      Visibilities: 9146
25 Column      1 (Size 1) contains U
26 Column      2 (Size 1) contains V
27 Column      4 (Size 1) contains DATE
28 Column      5 (Size 1) contains TIME
29 Column      6 (Size 1) contains IANT
30 Column      7 (Size 1) contains JANT
31 Column      3 (Size 1) contains SCAN

```

Comments:

**Line 1** Indicates the velocity frame. If not present in the table (as here), it is assumed to be LSR.

**Line 2** Indicates the filename associated to the currently displayed header.

**Lines 3-5** Display the dimensions of the associated array. Here it is a rank 2 array of dimension 103 *columns* times 9146 *lines*, *i.e.* 9146 visibility spectra of 32 frequency channels. Line 4 describes the frequency axis of the visibility spectra stored in the *uv* table. Be careful that this is a convention, *i.e.* it must be decoded using the particular form of the table. In our case, each spectra has 32 frequency channels of width -183.8 kHz, the frequency of the reference pixel 16.0 corresponding to 220398.688 MHz. This last frequency is the frequency delivered by the correlator, *i.e.* seen by the observatory. In particular, this is the frequency that must be used to compute the primary beam of the interferometer.

**Line 8** Indicates the unit of the real and imaginary parts of the visibilities, normally the Jansky (Jy).

**Line 9** Indicates that this is *uv* table (UV-DATA and RANDOM).



**Lines 10-13** Describe the coordinate system.

**Lines 14-15** Describe the projection system. In the *uv* table format, **A0** and **D0** indicate the phase center while **Right Ascension** and **Declination** indicate where the antenna pointed when acquiring the signal. These informations are in general identical for single field imaging and different for mosaicing.

**Lines 16** Indicates the baseline range in meters (m).

**Lines 17-19** Describe additional information about the frequency axis of the visibility spectra. In particular, the rest frequency (here 220398.688 MHz, that of the 13CO J=2-1 line) corresponding to a velocity of 6.3 km/s in the velocity frame indicated at line 1 (in general LSR). Frequencies are always in MHz, and velocities always in km/s.

**Line 20** Indicates the primary beam size of the interferometer in radian. This is an obsolescent way to pass the size of the interferometer antennas.

**Line 21** The noise section has no meaning for the UV table.

**Line 22** If present, proper motions are given in mas/yr. The epoch is used as the time origin.

**Line 23** If the TELESCOPE section is present, this line would indicate telescope name, its geographic coordinates and the antenna diameter (in m). This section contains also the information to compute the primary beam.

**Line 24** UV data section: number of channels, number of Stokes parameters and number of visibilities.

**Line 25 to end** Special columns description, including the 7 first ones and the **ntrail** trailing ones.

In particular, **Mosaic** *uv* tables contain two trailing columns named **L\_PHASE\_OFF**, **M\_PHASE\_OFF** for the so-called "Phase Offset Mosaics", or **X\_POINT\_OFF**, **Y\_POINT\_OFF** for the "Pointing Offset Mosaics", which contains the angular offsets of the field centers with respect to the Phase reference.

### 5.3 NOEMA: UV Tables from CLIC

For NOEMA, creating UV tables suitable for **IMAGER** is straightforward in **CLIC**. From a list of selected cross-correlation scans, the command **TABLE** creates a *uv* table with the appropriate format (or adds to an existing one). Mosaics are treated in much the same way: it is sufficient to add the **/MOSAIC** option to it.

### 5.4 ALMA: UV Tables from CASA

Importing *uv* data from CASA to **IMAGER** is a little more complex, because of the totally different design philosophy of the two packages. CASA intends to solve the *Measurement Equation*, whatever the complexity of this process. It is a all-in-one package for this purpose, where calibration and imaging are deeply intermixed and use a unified data format. As a result, a CASA Measurement Set is a complex architecture encompassing relations between many components stored as Tables in a directory-like tree. It can handle calibrated data, calibration tables, multisource data sets, raw data in the same architecture, allowing to retain all information to process complex images, such as multi-frequency synthesis of polarized emission observed in a mosaic of fields.

On the contrary, **IMAGER** works on calibrated data only, and with a single source (though possibly a mosaic) and single spectral setup at once.

The importation process goes through UVFITS data files, produced by `exportuvfits` from CASA, and imported through the `FITS` command of `SIC`. However, the UVFITS format is an incomplete standard, and to recover properly all associated informations, these two steps have been encapsulated in sophisticated scripts on each side.

#### 5.4.1 On the CASA side

The proper exportation is done by invoking the `casagildas()` tool.<sup>3</sup> `casagildas()` scans the Measurement Set using the `listobs()` tool, then uses a Python script that parses the output of `listobs()` to prepare a Python script named `casa.uvfits.py`.

It is then up to the user to execute this Python script, using the `casagildas("Do")` command that creates one UVFITS file per Source and Spectral window in the input Measurement Set. Thus, the sequence

```
vis='MyMeasurementSet.ms'  # Setup the input Measurement Set filename
casagildas()               # List its content and create the export script
casagildas("Do")           # Execute the export script
```

will create a set of

`Source-Frequency.uvfits`

files, where `Source` is the source name and `Frequency` is the central frequency of the spectral window in MHz, for all combinations of sources and spectral windows.

#### 5.4.2 On the IMAGER side

The UVFITS files have first to be converted to *uv* tables. This can be done by a simple script

```
sic find *.uvfits
for string /in dir%file
  @ fits_to_uvt 'string'
next
```

Each `Source-Frequency.uvfits` file will be converted to a `Source-Frequency.uvt` *uv* table (the original `.uvfits` file is kept too).

The `fits_to_uvt` script is based on the `FITS` command of `SIC`, but augmented with a number of tests to recognize the proper layout of the UVFITS file, as this layout depends on which CASA version was used, and whether it is a single source or multi source file.

The `fits_to_uvt` script has a number of options. Help can be obtained by typing

```
@ fits_to_uvt ?
```

Direct reading of UVFITS data is also partially supported: see Section 5.5.

#### 5.4.3 Current assumptions and limitations

GILDAS works in the LSR velocity frame and has limited polarization capabilities (`IMAGER` can only process one polarization state at a time, see Section 15 for details). Thus the `casagildas()` `-fits_to_uvt` sequence makes several assumptions:

---

<sup>3</sup>This tool is made available to CASA by `IMAGER` (`IMAGER` does not need to be active, but must have been executed once before)

- FDM (Frequency Division Mode) spectral windows are converted to LSR frame using the *mstransform* tool
- TDM (Time Division Mode) spectral windows, which have low spectral resolution (15 MHz), are assumed to be pure continuum data, and remain in the default frame of the original measurement set.
- The conversion from UVFITS to *uv* tables assumes that the data is unpolarized<sup>4</sup>, and merges the initial polarization states in an optimal way from the signal to noise point of view (i.e. using the respective weights of the two parallel hand states).
- *casagildas()* takes the same input parameters as the *listobs()* facility. Source and/or spectral window selection can thus be made by the user at this stage
- *casagildas()* takes the same input parameters as the *mstransform()* facility. Time integration may be done at this stage, but this may limit the performance of self-calibration at a later stage.

## 5.5 Reading UV tables

*uv* tables are simply read into **IMAGER** by **READ UV**. The rest frequency to be used to compute the velocity scale is normally found in the table, but can be overridden using the **READ /FREQUENCY** option. By default, the whole table is read, but a subset of the channels can be read using the **READ /RANGE** option (with the velocity scale as above).

UVFITS file may even be read directly as *uv* tables, applying the same conversion methods than the **fits\_to\_uv** script. However, this capability is still only partially supported. While it will work for basic (i.e. in memory) handling, full access to the *uv* data is only possible on the native format: this includes subset selection, as well as direct operations on *uv* data files through the **/FILE** option of many **UV...** commands.

## 5.6 UV Table handling

Besides the **READ UV** and **WRITE UV** commands to read or write *uv* tables, **IMAGER** has a number of commands to manipulate the current *uv* table buffer. These commands have names starting by **UV\_**. Most of them are in the **CLEAN** language, some in the **ADVANCED** one.

**IMAGER** works using UV buffers. Most commands only work on the current UV buffer, but some of them keep track of the previous buffer to allow the user to revert the operation.

**Data inspection and editing:** • **SHOW COVERAGE** display the *uv* coverage

- **SHOW UV** display the *uv* data
- **UV\_FLAG** allow flagging visibilities
- **UV\_PREVIEW** provides a quick view of the visibilities as a function of frequencies, and attempts to automatically find the continuum level and parts of the bandwidth with spectral line emissions.

**Data size reduction routines:** • **UV\_COMPRESS** is a simple spectral smoothing, providing only channel averaging by integer number of channels.

- **UV\_RESAMPLE** provides a more flexible spectral smoothing and resampling facility.

---

<sup>4</sup>unless the **/STOKES** option is present, see Section 15

- **UV\_TIME** can be used to time-average the UV data set, leading to faster processing. However, using **UV\_TIME** too early may limit your ability to perform accurate phase self-calibration.

**Continuum processing commands:** • **UV\_BASELINE** allows to remove the continuum baseline, by 0th or 1st order baseline fitting of each visibility.

- Conversely, **UV\_FILTER** will filter the spectral line range to leave only the channels with continuum emission. Both **UV\_BASELINE** and **UV\_FILTER** can use the results provided by **UV\_PREVIEW** to specify where spectral lines may be found.
- **UV\_CONTINUUM** converts a spectral line *uv* table into a bandwidth synthesis continuum *uv* table. **UV\_CONTINUUM** is only useful for UV plane analysis: see Section 10 for details.
- **UV\_MERGE /FILE** can merge several UV continuum tables with a specified spectral index to optimize the sensitivity.

**Image preparation:** • **UV\_CHECK** inspects the *uv* data to figure out how many different synthesized beams are needed.

- **UV\_SHORT** adds the short (or zero) spacing information provided by an additional single dish data, read by **READ SINGLE**.
- **UV\_STAT** evaluates the impact of robust weighting and tapering on the synthesized beam. It provides recommendations for the image and pixel sizes.
- **UV\_TRUNCATE** restricts the *uv* baseline length range.

**UV Plane analysis:** • **UV\_FIT** fit simple source models to the visibilities.

- **SHOW UV\_FIT** display the fit results, usually as a function of frequency, but also in other ways.

**Miscellaneous:** • **UV\_DEPROJECT** de-projects the (*u*, *v*) coordinates given a specified phase center, orientation and inclination. This can be useful for inclined, flattened, nearly axi-symmetric structures such as proto-planetary disks or galaxies.

- **UV\_CIRCLE** and **UV\_RADIAL** compute the azimuthal average of the visibilities. They are useful for rotationally symmetric structures such as proto-planetary disks or circum-stellar envelopes, for example.
- **UV\_REWEIGHT** changes the visibility weights.
- **UV\_SHIFT** changes the phase center. This can be useful for UV plane analysis.
- **UV\_MERGE /FILE** can merge several UV tables, Line or Continuum. It also allows stacking different spectral lines, by aligning them in velocity, as well as stacking emission from different sources.

The remaining **UV...** commands are related to imaging and deconvolution: **UV\_MAP** computes the dirty image, **UV\_RESTORE** computes the Clean image from a Clean component list by removal of the Clean components in the *uv* plane, and imaging of the residuals. **UV\_RESIDUAL** just computes the residuals by subtraction of the Clean components.

Finally, **UV\_SELF**, in the **CALIBRATE** language, is a specific variant of **UV\_MAP** used to compute the intermediate images required for self-calibration. It is not intended for direct use by normal users.

## 6 Single-field imaging and deconvolution

### 6.1 In a nutshell

```

1 read uv YourData
2 uv_stat
3 uv_map
4 clean
5 view clean
6 write * YourResult

```

1. Read your *uv* data
2. Have a look at its header, and get recommendations on image characteristics.
3. Image it
4. Deconvolve
5. see the result
6. Save the result if OK.

You are done. And this is often good. However, it may take a while, and the angular resolution and/or the brightness sensitivity may not be optimal. So, it may be worth for you to read the information below and adjust the control variables of **UV\_MAP**

### 6.2 Measurement equation and other definitions

The measurement equation of an instrument is the relationship between the sky intensity and the measured quantities. The measurement equation for a millimeter interferometer is to a good approximation (after calibration)

$$V(u,v) = \text{FT}\{B_{\text{primary}} \cdot I_{\text{source}}\}(u,v) + N \quad (1)$$

where  $\text{FT}\{F\}(u,v)$  is the bi-dimensional Fourier transform of the function  $F$  taken at the spatial frequency  $(u,v)$ ,  $I_{\text{source}}$  the sky intensity distribution,  $B_{\text{primary}}$  the primary beam of the interferometer (almost a Gaussian whose FWHM is the natural resolution of the single-dish antenna composing the interferometer),  $N$  some thermal noise and  $V(u,v)$  the calibrated visibility at the spatial frequency  $(u,v)$ . This measurement equation implies different kinds of problems.

1. The presence of noise leads to sensitivity problems.
2. The presence of the Fourier transform implies that visibilities belongs to the Fourier space while most (radio)astronomers are used to interpret images. A step of *imaging* is thus required to go from the *uv* plane to the image plane.
3. The multiplication of the sky intensity by the primary beam implies a distortion of the information about the intensity distribution of the source.
4. Finally, the main problem implied by this measurement equation is certainly the irregular, limited sampling of the *uv* plane because it implies that the information about the source intensity distribution is incomplete.

Deconvolution techniques are needed to overcome the incomplete sampling of the  $uv$  plane. To show how this can be done, we need additional definitions

- Let us call  $V = \text{FT} \{B_{\text{primary}} \cdot I_{\text{source}}\}$  the continuous visibility function.
- The sampling function  $S$  is defined as
  - $S(u, v) = 1/\sigma^2$  at  $(u, v)$  spatial frequencies where visibilities are measured by the interferometer.  $\sigma$  is the rms noise predicted from the system temperature, antenna efficiency, integration time and bandwidth. The sampling function thus contains information on the relative weights of each visibility.
  - $S(u, v) = 0$  elsewhere.
- We finally call  $B_{\text{dirty}} = \text{FT}^{-1} \{S\}$  the dirty beam.

If we forget about the noise, we can thus rewrite the measurement equation as

$$I_{\text{dirty}} = \text{FT}^{-1} \{S \cdot V\}. \quad (2)$$

Using the property #1 of the Fourier transform (see Appendix), we obtain

$$I_{\text{dirty}} = B_{\text{dirty}} * \{B_{\text{primary}} \cdot I_{\text{source}}\}, \quad (3)$$

where  $*$  is the convolution symbol. Thus, the incompleteness of the  $uv$  sampling translates into the image plane as a convolution by the dirty beam, implying the need of deconvolution. From the last equation, it is easy to show that the dirty beam is the point spread function of the interferometer, *i.e.* its response at a point source. Indeed, for a point source at the phase center,  $\{B_{\text{primary}} \cdot I_{\text{source}}\} = I_{\text{point}}$  at the phase center and 0 elsewhere and the convolution with a point source is equal to the simple product:  $I_{\text{dirty}} = B_{\text{dirty}} \cdot I_{\text{point}} = B_{\text{dirty}}$  for a point source of intensity  $I_{\text{point}} = 1$  Jy.

We note that Fourier transform are in general done through Fast Fourier Transform, which implies first a stage of re-interpolation of the visibilities on a regular grid in the  $uv$  plane, a process called *gridding*. This gridding step introduces a convolution in the  $uv$  space, and thus a multiplication by the Fourier transform of the gridding function in the image plane, which needs to be corrected later by division by this Fourier transform. It can be shown that despite this step, the convolution property mentioned before still holds.

### 6.3 Imaging

The process known as *imaging* consists in computing the dirty image and the dirty beam from the measured visibilities and the sampling function.

#### 6.3.1 Image size and pixel size

**Link between image size and  $uv$  cell size** The gridding stage requires at least Nyquist sampling of the  $uv$  plane to avoid the artifact known as aliasing. This sampling depends on the source size.

For the signal, the source size is limited by the primary beam, so that the Nyquist sampling in the  $uv$  plane is obtained with a size of the grid cells equals to half the size of the antenna diameter. (this is the smallest spatial frequency that the interferometer can be sensitive to, *i.e.*

the natural resolution in the  $uv$  plane). In the image plane, this implies to make an image at least twice as large as the primary beam size (see Fourier transform property #2 in Appendix).

Unfortunately, the spatial frequencies of the noise are not bound: the noise increases at the edges of the produced image because of the noise aliasing and gridding correction.

Unless you have good reasons (such as a strong confusion source close to the primary beam), you should not choose too large an image size, since that would slow down imaging and deconvolution.

**Link between pixel size and largest  $uv$  spatial frequency** The largest sampled spatial frequency is directly linked to the synthesized beam size (*i.e.* the interferometer spatial resolution). The pixel size must be at least 1/2 the synthesized beam size to ensure Nyquist sampling in the image plane. However, Nyquist sampling is enough only when dealing with linear processes while deconvolution techniques are non-linear. It is thus recommended to select a pixel size between 1/3 and 1/4 of the synthesized beam to ease the deconvolution. Smaller pixel sizes would lead to larger images, and unduly slow down the imaging and deconvolution process.

### 6.3.2 Weighting and Tapering

The use of the visibility weights ( $1/\sigma^2$ ) in the definition of the sampling function is called natural weighting as it is natural to weight each visibility by the inverse of noise variance. Natural weighting is also the way to maximize the point source sensitivity in the final image. However, the exact scaling of the sampling function is an additional degree of freedom in the imaging process. In particular, the user may change this scaling to give more or less weight to the long or short spatial frequencies.

We can thus introduce a weighting function  $W(u, v)$  in the definitions of  $B_{\text{dirty}}$  and  $I_{\text{dirty}}$

$$B_{\text{dirty}} = \text{FT}^{-1} \{W.S\} \quad (4)$$

and

$$I_{\text{dirty}} = \text{FT}^{-1} \{W.S.V\}. \quad (5)$$

There are two main categories of weighting functions

**Robust weighting** In this case,  $W$  is computed to enhance the contribution of the large spatial frequencies. This is done by first computing the natural weight in each cell of the  $uv$  plane. Then  $W$  is derived so that

- The product  $W.S$  in a  $uv$  cell is set to a constant if the natural weight is larger than a given threshold;
- $W = 1$  (*i.e.* natural weighting) otherwise.

This decreases the weight of the well measured  $uv$  cells (*i.e.* very low noise cells) while it keeps natural weighting of the noisy cells. It happens that the cells of the outer  $uv$  plane (corresponding to the large interferometer configurations) are often noisier than the cells of the inner  $uv$  plane (just because there are less cells in the inner  $uv$  plane). Robust weighting thus increases the spatial resolution by emphasizing the large spatial frequencies at moderate cost in sensitivity for point sources (but with a larger loss for extended sources, see below).

**Tapering** is the apodization of the  $uv$  coverage by simple multiplication by a Gaussian

$$W = \exp \left\{ -\frac{(u^2 + v^2)}{t^2} \right\}, \quad (6)$$

where  $t$  is the tapering distance. This multiplication in the  $uv$  plane translates into a convolution by a Gaussian in the image plane, *i.e.* a smoothing of the result. The only purpose of this is to increase the sensitivity to extended structure. Tapering should never be used **alone** as this somehow implies that you throw away large spatial frequencies measured by the interferometer. It is only a way to extract the most information from the given data set. If you need more sensitivity to extended structures, use compact configuration of the arrays rather than extended configurations and tapering.

For more details on the whole imaging process the interested reader is referred to Guilloteau (2000).

### 6.3.3 Implementation (READ UV, UV\_MAP and UV\_STAT)

In **IMAGER**, gridding in the  $uv$  plane and computation of the dirty beam and image are coded in the **UV\_MAP** command. This command works on an internal buffer containing the  $uv$  table read from a file through the **READ UV** command.

The **UV\_MAP** command is controlled by a set of SIC variables named with the prefix **MAP\_**. Suitable defaults are provided, so that only specific cases should require customization by the user. A description of the all variables can be obtained through **HELP UV\_MAP**. **UV\_MAP ?** also gives their default and current values.

#### Basic usage - image characterization:

Name	Dim/Type	Description
<b>BEAM_STEP</b>	Int	Number of channels per common dirty beam, if $> 0$ . If 0 (default value), only one beam is produced in total. If $-1$ , an automatic guess is performed from the map size and requested precision ( <b>MAP_PRECIS</b> ).
<b>MAP_CELL</b>	[2] Real	Pixel size in arcsecond. Enter 0,0 to let the task find the best values.
<b>MAP_FIELD</b>	[2] Real	Image size in arcsecond. <b>MAP_FIELD</b> has precedence over the number of pixels <b>MAP_SIZE</b> to define the actual map size when both variables are non-zero.
<b>MAP_SIZE</b>	[2] Int	Image size in pixels
<b>MAP_CENTER</b>	Char.	A character string to specify the new Map center and the new map orientation, see the next subsection related to the definition of the projection center of the image.

#### Weighting:



<code>MAP_ROBUST</code>	Real	Robust weighting factor, in range 0 - $+\infty$ . 0 means Natural weighting (as $+\infty$ , actually). 0.5 or 1 is usually a good choice for Robust Weighting. Default is 0, i.e. natural weighting. (Old name <code>UV_CELL[1]</code> )
<code>MAP_UVTAPER</code>	[3] Real	Array of 3 values controlling the UV taper: major/minor axis at 1/e level [m,m] (first two values), and position angle ([deg], third value). By default (0,0,0). (Old name <code>UV_TAPER[3]</code> ).
<code>MAP_UVCELL</code>	[2] Real	UV Cell size for Robust weighting. Default is 0, meaning that the cell size is derived from the antenna diameter. (Old name <code>UV_CELL[2]</code> )
<code>MAP_TAPEREXPO</code>	Real	the taper exponent. Default 2, indicating Gaussian function. (Old name <code>TAPER_EXPO</code> ).
<b>Advanced:</b>		
<code>MAP_PRECIS</code>	Real	Position precision at the map edge, in fraction of pixel size, used (with the actual image size) to derive the actual number of channels which can share the same beam. Default value is 0.1.
<code>MAP_POWER</code>	Int	Rounding scheme for default image size, to numbers like $2^n 3^p 5^q$ . $p$ and $q$ are less than or equal to <code>MAP_POWER</code> . Default value is 2, for smallest image size. For <code>MAP_POWER</code> = 0 <code>MAP_SIZE</code> is just a power of 2.
<code>MAP_ROUNDING</code>	Real	Maximum error between optimal size ( <code>MAP_FIELD</code> / <code>MAP_CELL</code> ) and rounded (as a power of $2^k 3^p 5^q$ ) <code>MAP_SIZE</code> .
<code>MAP_TRUNCATE</code>	Real	For a Mosaic, truncate the primary beam to the specified level (in fraction). Default value is 0.2.
<b>Debug:</b>		
<code>MAP_CONVOLUTION</code>	Int	Gridding convolution mode in the $uv$ plane. (default 5 for speroidal functions) (old name <code>CONVOLUTION</code> )
<code>MAP_VERSION</code>	Int	Version of code to be used. This is a temporary variable to allow comparison between the new and old codes without quitting <b>IMAGER</b> .

Parameters can be listed by the commands `UV_MAP ?` and `CLEAN ?`. More details are obtained using `??` or `???` as arguments instead of `?`. A thorough description of each parameter can be obtained by typing: `help UV_MAP MAP_*` or `help CLEAN CLEAN_*`.

IMAGER> UV\_MAP ?

UV\_MAP makes a dirty image and a dirty beam from the UV data

Behaviour is controlled by a number of SIC Variables

- BEAM\_STEP and MAP\_PRECIS control the dirty beam precision
- MAP\_CENTER controls shifting and rotation
- MAP\_CELL[2], MAP\_SIZE[2], MAP\_FIELD[2] control the map sampling
- MAP\_UVTAPER[3], MAP\_UVCELL and MAP\_ROBUST control the beam shape and weighting scheme

----	Basic parameters		Selected	Recommended
	Map Size (pixels)	MAP_SIZE	[ 0 0 ]	[ 0 0 ]
	Field of view (arcsec)	MAP_FIELD	[ 0 0 ]	[ 0 0 ]
	Pixel size (arcsec)	MAP_CELL	[ 0 0 ]	[ 0 0 ]
	Map center	MAP_CENTER	[ ]	

Robust weighting parameter	MAP_ROBUST	[ 0 ]	
UV cell size (meter)	MAP_UVCELL	[ 0 ]	[ 0 ]
UV Taper (m,m,)	MAP_UVTAPER	[ 0 0 0 ]	

### 6.3.4 Defining the Projection Center of the image

The command `UV_MAP` handles phase tracking center through its arguments, or through the string variable `MAP_CENTER`. The syntax of the arguments is the following:

`UV_MAP [CenterX CenterY UNIT] [Angle] [/FIELDS FieldList] [/TRUNCATE Percent]`

The allowed syntax for `MAP_CENTER` is described by `HELP UV_MAP MAP_CENTER`.

### 6.3.5 Typical imaging session

```

1 read uv gag_demo:demo-single-imager
2 uv_map ?
3 uv_stat weight
4 let map_robust 0.5
5 uv_map ?
6 uv_map
7 show beam
8 show dirty
9 let map_size 128
10 uv_map
11 show beam
12 show dirty
13 hardcopy demo-dirty /dev eps
14 write dirty demo
15 write beam demo
```

Comments:

**Step 1** Read the `demo-single-imager.uvt` *uv* table in an internal buffer.

**Step 2** Check current state of the variables that control the imaging.

**Steps 3-5** Select the robust weighting threshold (step 4) from the result of the `UV_STAT` command (step 3) and recheck the current state of the variables that control the imaging (step 5).

**Steps 6-8** Image and plot the dirty beam and image.

**Steps 9-12** Try a smaller size of the map as the default imaged field-of-view looked too large from previous plots.

**Steps 13** Make a Post-Script file from the dirty image.

**Steps 14-15** Write dirty image and beam in `demo.lmv` and `demo.beam` files for deconvolution in a future `IMAGER` session. These steps are optional as you may directly proceed to the deconvolution stage without writing the files.

## 6.4 Deconvolution

Once the dirty beam and the dirty image have been calculated, we want to derive an astronomically meaningful result, ideally the sky brightness. However, it is extremely difficult to recover

the intrinsic brightness distribution with an interferometer. Mathematically, the incomplete sampling of the  $uv$  plane implies that there is an infinite number of intensity distributions which are compatible with the constraints given by the measured visibilities. Fortunately, physics allow us to select some solutions from the infinite number that mathematics authorize. The goal of deconvolution is thus to find a sensible intensity distribution compatible with the measured visibilities. To reach this goal, deconvolution needs 1) some *a priori*, physically valid, assumptions about the source intensity distribution and 2) as much knowledge as possible about the dirty beam and the noise properties (in radioastronomy, both are well known). The best solution would obviously be to avoid deconvolution, *i.e.* to get a Gaussian dirty beam. For instance, the design of the compact configuration of ALMA has been thought with this goal in mind. However, this goal is out of reach for today's millimeter interferometers, even ALMA.

The simplest *a priori* knowledge that the user can feed to deconvolution algorithm is a rough idea of the emitting region in the source. The user defines a support inside which the signal is to be found while the outside is only made of sidelobes. The definition of a support considerably helps the convergence of deconvolution algorithms because it decreases the complexity of the problem (*i.e.* the size of the space to be searched for solutions). However, it can introduce important biases in the final solution if the support excludes part of the sky region that is really emitting. Support must be thus used with caution.

## 6.5 The family of CLEAN algorithms ( HOGBOM, CLARK, MX, SDI, MRC, MULTI)

Radio astronomy interferometry made a significant step forward with the introduction of a robust deconvolution algorithm, known as CLEAN, by Högbom (1974).

### 6.5.1 CLEAN ideas

The family of CLEAN algorithms is based on the *a priori* assumption that the sky intensity distribution is a collection of point sources. The algorithms have three main steps

#### Initialization

- of the residual map to the dirty map;
- and of the clean component list to a NULL (*i.e.* zero) value.

**Iterative search** for point sources on the residual map. As those point sources are found,

- they are subtracted from the residual map;
- and then they are logged in the clean component list.

**Restoration** of the clean map 1) by convolution of the clean component list with the clean beam, *i.e.* a Gaussian whose size matches the synthesized beam size and 2) by addition of the residual map.

**Stopping criteria** Several criteria may be used to stop the iterative search of this “matching pursuit”:

1. When the maximum of the absolute value of the residual map is lower than a fraction of the noise. This stopping criterion is adapted to *noise limited situations*, *i.e.* when empirical measures of the noise in the cleaned image give a value similar to the noise value estimated from the system temperatures.

2. When the maximum of the absolute value of the residual map is lower than a fraction of the maximum intensity of the original dirty map. This stopping criterion is adapted to *dynamic range limited situations*, *i.e.* when some part of the source is so intense that the associated side lobes are larger than the thermal noise. In this case, any empirical measure of the noise in the cleaned image will give a value larger than the noise value estimated from the system temperatures.
3. The total number of clean components. This is a sanity criterium in case the other ones would be badly tuned.
4. When the total flux remains stable.

Choosing the good stopping criterion is important because the deconvolution must go deep enough to recover weak extended flux but CLEAN algorithms start to diverge when the noise is cleaned too deep. Criterion 4 is thus in general preferable, but may lead to insufficient cleaning when the dirty beam is poor (by lack of *uv* coverage and/or because of phase noise). If (# 4) fails, a good compromise is to clean down to or slightly below (typically  $0.8\sigma$ ) the noise level.

**Stability criterion** The simplest way to control the convergence is the `CLEAN_STOP` character variable. It allows to express the stopping threshold in natural units, e.g. Jy, mJy, K, milliK, Noise or Sigma (the noise levels), or even % for peak percentage.

But Clean convergence can also be controlled by the usual `CLEAN_ARES` (#1, maximum Absolute RESidual value), `CLEAN_FRES` (#2, maximum Fractional RESidual value) and `CLEAN_NITER` (#3, maximum Number of ITERations) criteria, plus `CLEAN_NCYCLE` for methods with major cycles. A fourth criterium (#4) is *convergence*, which is controlled by `CLEAN_NKEEP`, a number of components. Deconvolution of a given channel stops if the cumulative flux at iteration number  $N$  is smaller (resp. larger) than at iteration  $N - \text{CLEAN\_NKEEP}$  for positive signals (resp. negative). In essence, `CLEAN_NKEEP` is the number of components when the signal is just above the noise. Experimentation with various types of images has shown that `CLEAN_NKEEP` = 70 is a good compromise.

However, criteria #1-3 can be set to 0, allowing `IMAGER` to automatically guess when to stop. In this case, `IMAGER` uses an absolute residual threshold equals to the noise level (available in `dirty%gil%noise`), and estimates a (very conservative) maximum number of Clean components.

Using `CLEAN_STOP` has precedence over the other ways of specifying the stopping criteria.

**Formation of the CLEAN map** The clean component list may be searched on an arbitrarily fine spatial grid without too much physical sense as the interferometer has a finite spatial resolution. The convolution by the clean beam thus reintroduces the finite resolution of the observation, an information which is missing from the list of clean components alone. This step is often called *a posteriori* regularization.

The shape (principally its size) of the clean beam used in the restoration step plays an important role. The clean beam is usually a fit of the main lobe (*i.e.* the inner part) of the dirty beam. This ensures that 1) the flux density estimation will be correct and 2) the addition of the residual map to the convolved list of clean component makes sense (*i.e.* the unit of the clean and residual maps approximately matches).

The final addition of the residual map plays a double role. First, it is a first order correction to insufficient deconvolution. Second, it enables noise estimate on the cleaned image since the residual image should be essentially noise when the deconvolution has converged.

Some odd dirty beams may lead to incorrect flux measurements. For example, if the dirty beam has a very narrow central peak superimposed on a rather broad plateau, the volume of the Gaussian fitted to the central peak does not match that of the dirty beam, and the flux scale will be incorrect. Data-reweighting is required to cure these peculiar situations, and this always implies a loss of sensitivity.

Super-resolution is the fact of restoring with a clean beam size smaller than the fit of the main lobe of the dirty beam. The underlying idea is to get a bit finer spatial resolution. However, it is a bad practice because it breaks the flux estimation and the usefulness of the addition of the residual maps. It is better to use robust weighting to emphasize the largest measured spatial frequencies.

### 6.5.2 Basic CLEAN algorithms (HOGBOM, CLARK and MX)

The main difference between the different basic CLEAN algorithms is the strategy for searching the point sources.

**HOGBOM** The simplest strategy of the iterative search was introduced by Högbom (1974). It works as follows

1. Localization of the strongest intensity pixel in the current residual map:  $\max(|I_{\text{res}}|)$ .
2. Add  $\gamma \cdot \max(|I_{\text{res}}|)$  and its spatial position to the clean component list.
3. Convolution of  $\gamma \cdot \max(|I_{\text{res}}|)$  by the dirty beam.
4. Subtract the resulting convolution from the residual map in order to clean out the side lobes associated to the localized clean component.

$\gamma$  is the loop gain. It controls the convergence of the method. In theory,  $0 < \gamma < 2$ .  $\gamma = 1$  would in principle give faster convergence, since the remaining flux at one position is  $\propto (1 - \gamma)^{n_{\text{comp}}}$ , where  $n_{\text{comp}}$  is the number of clean components found at this position. But, in practice, one should use  $\gamma \simeq 0.1 - 0.2$ , depending on sidelobe levels, source structure and dynamic range. Indeed, deviations (such as thermal noise, phase noise or calibration errors) from an ideal convolution equation force to use low gain values in order to avoid non linear amplifications of errors.

An important property of **HOGBOM** algorithm is that only the inner quarter of the dirty image can be properly cleaned when dirty beam and images are computed on the same spatial grid. Indeed, the subtraction of the dirty sidelobes associated to any clean component is possible only in the spatial extent of the dirty beam image. When the user defines a support (*a priori* knowledge), the cleaned region becomes even smaller than the inner quarter of the dirty map.

**CLARK** The most popular variant to the **HOGBOM** algorithm is due to Clark (1980). The iterative search for point sources involves minor and major cycles.

**In minor cycles**, an **HOGBOM** search is performed with two limitations: 1) Only the brightest pixels are considered in the above step 1, and 2) the convolution of the found point sources (step 3 above) is done with a spatially truncated dirty beam <sup>5</sup>. Both limitations fasten the search but may lead to difficult convergence in cases where the secondary side lobes are a large fraction (*e.g.* 40%) of the main side lobe.

---

<sup>5</sup>It is also theoretically possible to do so with an intensity truncated beam.

In **major cycles**, the clean components found in the last minor cycle are removed in a single step from the residual map in the Fourier plane. The use of the Fourier transform enable to clean slightly more than the inner quarter of the map.

**CLARK** is faster than **HOGBOM**, but less stable.

**MX** The **MX** (or Cotton-Schwab, from the names of its authors) algorithm, due to Schwab (1984), is a variant of the **CLARK** algorithm in which the clean components are removed from the  $uv$  table at each major cycle. This is the most precise way of removing the found clean components because it avoids aliasing of the dirty sidelobes. A direct consequence is that this method enables to clean the largest region of the dirty map. However, this may be a relatively slow algorithm because the imaging step must be redone at each major cycle, although this speed issue could be compensated by the ability to use smaller images.

### 6.5.3 Advanced CLEAN algorithms to deal with extended structures (**SDI**, **MULTI** and **MRC**)

When the spatial dynamic of the imaged source is large (*i.e.* when the ratio of the largest source structure over the synthesized resolution is large), the basic **CLEAN** algorithms may (rarely) turn smooth area of the source into a serie of ridges and stripes. Indeed, when the dirty beam pattern is subtracted from a smooth feature of the dirty map, the sidelobes patterns appear in the residual map. The search for the next clean component will then pick first the pixels in the sidelobes pattern amplifying this pattern. Several variants of **CLEAN** have been devised to solve this problem.

**SDI** In the **CLEAN** variant proposed by Steer et al. (1984), extended features (instead of point sources) around the current maximum of the residual map are selected and removed in a single step. The simplest implementation redefines the notion of minor and major cycles of the **CLARK** algorithm. In the minor cycles, only the selection of the clean components is done by including all the pixels in the residual map that rise above a contour set at some fraction of the current peak level. In major cycles, all those components are removed together in the Fourier plane. The **SDI** algorithm may be instable if the fraction used for the selection of the clean components is badly chosen. **SDI** is very sensitive to the support selection.

**MRC** The Multi Resolution Clean **MRC** from Wakker & Schwarz (1988) is the first attempt to introduce the notion of cleaning at different scales. **MRC** works on two intermediate maps (strictly speaking **MRC** is a double-resolution **CLEAN** algorithm). The first map is a smoothed version of the dirty map and the second map, called difference map, is obtain by subtraction of the smoothed map from the original dirty map. Since the measurement equation is linear, both maps can be cleaned independently (using a smoothed and a difference dirty beam, respectively). The underlying idea is that extended sources in the dirty map will look like more "point-like" with respect to the smoothed dirty beam in the smoothed map. **MRC** is faster than the basic **CLEAN** algorithms because fewer clean components are needed to reproduce an extended source feature in the smoothed map than in the original map.

**MULTI** The Multi-scale **CLEAN** algorithm has also been designed to improve the performance of **CLEAN** for extended sources. It is a straightforward extension of **CLEAN** that models the sky brightness by the summation of blobs of emission having different size scales. It is equivalent

to simultaneously deconvolve images obtained with different synthesized beams derived from the highest resolution one by convolution kernels. This algorithm works simultaneously in a range of specified scales. Multi-scale CLEAN can produce good images with a loop gain of 0.5 or even higher.

The implementation of Multi-scale CLEAN in **IMAGER** slightly differs from that of CASA. It is less optimized in terms of speed, but uses a better convergence scheme in which the scale chosen at each iteration is the one with best signal to noise ratio. Accordingly, it is more stable. Only 3 scales are used so far in **IMAGER**, with a size ratio controlled by **CLEAN\_SMOOTH**.

#### 6.5.4 Implementation and typical use

Deconvolution parameters are controlled by **CLEAN\_\*** variables. Progress has been made on automatic guess for Cleaning parameters. The table below presents the current naming scheme, with previous or equivalent names mentioned in parentheses, since these names were (or are still) used by several older packages such as **MAPPING**, AIPS or CASA. The equivalent "old" names (mentioned in Upper case below) will remain as aliases, while those mentioned in mixed case have disappeared as they were seldom used before.

<b>CLEAN_STOP</b>	Stopping value and its Unit
<b>CLEAN_ARES</b>	Absolute residual (ARES)
<b>CLEAN_FRES</b>	Fractional residual (FRES)
<b>CLEAN_GAIN</b>	Loop gain (GAIN)
<b>CLEAN_INFLATE</b>	Inflation factor allowed to display MultiScale clean components
<b>CLEAN_METHOD</b>	Cleaning Method (METHOD)
<b>CLEAN_NCYCLE</b>	Maximum number of Major cycles (Nmajor)
<b>CLEAN_NITER</b>	Maximum number of iterations (NITER)
<b>CLEAN_NGOAL</b>	A number of components for ALMA joint deconvolution only (Ngoal)
<b>CLEAN_NKEEP</b>	Number of iterations used to check convergence (see below)
<b>CLEAN_POSITIVE</b>	Minimum number of positive Clean components
<b>CLEAN_RATIO</b>	Ratio for Dual Resolution clean (Ratio)
<b>CLEAN_SEARCH</b>	Minimum primary beam threshold for searching (Search_W)
<b>CLEAN_SMOOTH</b>	Smoothing factor for Multi Scale Clean (Smooth)
<b>CLEAN_SPEEDY</b>	Speeding factor for Clark (Spexp)
<b>CLEAN_TRUNCATE</b>	Minimum primary beam threshold for restoring (Restore_W)
<b>CLEAN_WORRY</b>	"Worry" factor for Clark (Worry)

**Implementation** In **IMAGER**, the variants of the CLEAN algorithms discussed above are coded as the following commands: **HGOBOM**, **CLARK**, **MX**, **SDI**, **MULTI** and **MRC**. All those commands work on two internal buffers containing the dirty beam and dirty image. Both buffers are created directly from *uv* table through the **UV\_MAP** command, or they can be loaded from files through the **READ BEAM** and **READ DIRTY** commands. The behavior of those commands is controlled through the following common **SIC** variables:

#### Iterative search

- CLEAN\_POSITIVE** Number of positive clean components to be found before enabling the search for negative components. Default is 0.
- CLEAN\_GAIN** Loop gain. Default is 0.2, good compromise between stability and speed.



## Stopping criteria

**CLEAN\_STOP** Compact way to specify the stopping criterium. Default is currently empty, but might be set to **2 SIGMA** as a good general default.

**CLEAN\_NITER** Maximum number of clean components. Default is 0.

**CLEAN\_FRES** Maximum amplitude of the absolute value of the residual image. This maximum is expressed as a fraction of the peak intensity of the dirty image. Default value is 0.

**CLEAN\_ARS** Maximum amplitude of the absolute value of the residual image. This maximum is expressed in the image units (Jy/Beam). Default value is 0.

**CLEAN\_NKEEP** Minimum number of Clean components before testing if Cleaning has converged. Default value is 70.

## Support

**BLC and TRC** Bottom Left Corner and Top Right Corner of a square support in pixel units. Default is 0, which means using only the inner quarter if no other support is defined.

**SUPPORT** A command that defines the support where to search for clean components. The support can be a Mask, or a Polygon. For a Polygon, the definition can be interactive, using the **GREG** cursor. This definition can be stored in a file through the **WRITE SUPPORT** command and read back in memory from the file with the **SUPPORT** command. The polygon support definition is stored in the **SUPPORT%** structure. Command **SUPPORT /MASK** instructs **IMAGER** to use the Mask instead of the polygon for the Clean support.

**MASK** Command **MASK** is used to define a Mask-like support. This can be interactive, or automatic using a thresholding technique in command **MASK THRESHOLD**. The computed Mask can be saved by command **WRITE MASK**. The Mask can also be read by command **READ MASK**. Command **MASK USE** is equivalent to command **SUPPORT /MASK**, and instructs **IMAGER** to use the Mask instead of the polygon for the Clean support.

## Clean beam parameters

**BEAM\_SIZE** is a 3-element array that gives the FWHM size of the major and minor axes (in arcsec) and position angle (in degree) of the Gaussian used to restore the clean image from the clean component list. Default is all parameters at 0, meaning use the fit of the main lobe of the dirty image. Changing the default value of those parameters is dangerous. The beam size effectively used is available in **BEAM.FITTED**.

Other variables control specific aspects of a subclass of the **CLEAN** algorithm:

**CLEAN\_NCYCLE** Maximum number of major cycles in all algorithms using this notion (**CLARK**, **MX**, **SDI**). Default is 50.

**BEAM\_PATCH** Size (in pixel units) of the dirty beam used to deconvolve the residual image in minor cycles. It is used in **CLARK** and **MRC** algorithms only. Default value is 0. This is for development only.

**CLEAN\_SMOOTH** Smoothing factor between different scales in the **MULTISCALE** methods. Default value is  $\sqrt{3}$ .

**CLEAN\_RATIO** Smoothing factor between different scales in the **MRC** method. Default value is 0, for which the code automatically derives the best power of 2 adequate for the current problem.



### 6.5.5 Restoring step: `UV_RESTORE`

`CLEAN` (except for `MRC`) has three outputs: the `CLEAN` image itself, the `RESIDUAL` image, and the list of point sources (the Clean Components) that reproduce the observed visibilities, the `CCT` table.

An aesthetically better results, with better noise properties, can be obtained after `CLEAN` by removing the Clean Components from the measured visibilities, and re-imaging this to produce the `RESIDUAL` image. Aliasing at map edges is then minimized, as it only concerns noise if the deconvolution was reasonable. As mentioned previously, this is implicitly done when using `MX` instead of `CLEAN`. It can also be done after `CLEAN` using command `UV_RESTORE`.

This step can also be used to properly scale the residuals when the synthesized beam is not well fit by a Gaussian, or when all channels do not share the same beam (see Section 4.5). This is done through the use of the so-called `JvM factor`. This factor, introduced in Jorsater & van Moorsel (1995), estimates the ratio of clean beam area to dirty beam area, and is stored in variable `BEAM_JVM` and (on a per beam basis) `BEAM_VALUES[4]` which are computed by `FIT /JVM_FACTOR`. Residuals are multiplied by this factor (on a channel per channel basis if needed), allowing to first order to scale the residuals to the same unit as the Cleaned data, i.e. Jy/beam area.

In general, this number is fairly close to 1. However, when several observing configurations have been merged together, the synthesized beam often exhibits a central peak over a larger plateau, because of the higher weights of short baselines. Robust weighting limits the effect, but is not able to suppress it totally. In such cases, the `JvM factor` can be of order 0.5 to 0.6.

- **Caveat:** This scaling is only meaningful to first order for (reasonably) extended sources and well-behaved beams. It should NOT be used to analyze data for point sources.

`UV_RESTORE` uses the `JvM factor` if `FIT /JVM_FACTOR` has been used before. It also uses the mean Clean beam geometry defined by `BEAM_FITTED`.

### 6.5.6 Typical deconvolution session

```

1 read beam demo
2 read dirty demo
3 clean ?
4 hogbom /flux 0 1
5 show residual
6 show clean
7 write clean demo
8 let name demo
9 show noise
10 let ares 0.5*noise
11 clean ?
12 hogbom /flux 0 1
13 let niter 2000
14 clean ?
15 hogbom /flux 0 1
16 show residual
17 show clean
18 for iplane 1 to 10
```

```

19  show clean iplane
20  support
21  hogbom iplane /flux 0 1
22  write support "demo-" 'iplane'
23 next iplane
24 show residual
25 view cct
26 view clean
27 write residual demo
28 write clean demo
29 write cct demo

```

Comments:

**Steps 1-2** Read dirty beam and dirty image from the `demo.beam` and `demo.lmv` files. Those steps are not needed if the dirty beam and image are already stored in the internal buffer, *i.e.* if you have imaged the *uv* table just before in the same **IMAGER** session.

**Steps 3-6** Print the current state of the control parameters, deconvolve the dirty image using the **HOGBOM** algorithm (step 3) and look at the results (residual and clean images). The `/flux 0 1` option pop-up the visualization of the cumulative flux deconvolved as the clean components are found.

**Steps 8-12** Estimate the empirical noise through the **SHOW NOISE** command after this first deconvolution and set the `ares` stopping criterion accordingly. Check that the new value of `ares` has been correctly set (step 11) and restart deconvolution.

**Steps 13-17** Increase the number of clean components as the previous deconvolution stopped before the residual image reached the `ares` value. Restart deconvolution and look at results.

**Steps 18-23** Attempt to improve deconvolution by definition of a support per plane and deconvolve this plane accordingly. The support is stored in a file for further re-use. The deconvolution results are then displayed.

**Steps 24-26** Display the residual images, visualize the cumulative flux as a function of the clean component number and visualize the clean spectra cube in an interactive way.

**Steps 27-29** Write residual image, clean image and clean component list in `demo.lmv-res`, `demo.lmv-clean` and `demo.cct` files for later use.

Typical deconvolution session using other **CLEAN** algorithm would look very similar. The main difference would be the possible tuning of other control parameters. A deconvolution session using **MX** would start differently as the imaging and deconvolution are done in the same step:

```

1 read uv demo
2 mx ?
3 mx /flux 0 1
4 show residual
5 show clean
6 write * demo
% 6 write beam demo
% 7 write dirty demo
% 8 write clean demo

```

```
%      9 write residual demo
%      10 write cct demo
```

Comments:

**Step 1** Read the `demo.uvt` *uv* table in an internal buffer.

**Step 2** Check current state of the variables that control the imaging and deconvolution.

**Steps 3-5** Deconvolve and look at the results.

**Steps 6-10** Write all the internal buffers on disk files.

All the tuning of the typical imaging and deconvolution sessions could be used in this **MX** session although they are not repeated here.

## 6.6 Practical advices

### 6.6.1 Comparison of deconvolution algorithms

**HOGBOM** is the basic **CLEAN** algorithm. It is very robust, but somewhat slow although this is partially compensated by good parallel programming. **CLARK** introduces a faster strategy for the search and removal of clean component. However, it may converge more slowly and can even be instable when dirty sidelobes are high, or the phase noise still significant. **MX** cleans the largest region of the dirty map because the source removal happens in the *uv* plane. For the same map size, it is slower than **CLARK** because of the repeated imaging step, but smaller image sizes can be used. It shares some of the **CLARK** instabilities because it uses the same search strategy, but the removal strategy counteracts this. **MX** can be very slow for large number of visibilities.

**HOGBOM**, **CLARK** and **MX** may introduce artifacts as parallel stripes in the clean map when dealing with smooth, extended structures. **SDI**, **MRC** and **MULTI** introduce a different (in principle better) handling of those extended sources. **SDI** is a rough attempt and requires a good prior of the support to work correctly. **MRC** and **MULTI** introduce the notion of cleaning at different spatial scales. **MRC** has unfortunately no notion of Clean Components. **MULTI** is the most advanced tool, but is significantly slower than any other method.

### 6.6.2 A few (obvious) practical recommendations

**Map size** Make an image about twice the size of the primary beam (*e.g.*  $2 \times 55''$  at 90 GHz and  $2 \times 22''$  at 230 GHz for NOEMA antenna) to ensure that all the area of the primary beam (inner quarter of the dirty map) will be cleaned whatever the deconvolution algorithm is used. However, avoid making a too large dirty image because the **CLEAN** algorithms will then try to deconvolve region outside the primary beam area where the noise dominates.

**Support** Start your first deconvolution *without* any support to avoid biasing your clean image. If the source is spatially bound, you can define a support around the source and restart the deconvolution with this *a priori* information. Be careful to check that there is no low signal-to-noise extended structure that could contain a large fraction of the source flux outside your support... Avoid defining a support too close to the natural edges of your source. Indeed, deconvolving noisy regions around your source is advisable because it ensures that you do not bias your deconvolution too much.

**Stopping criterion** Choose the right stopping criterion.

Use the stability **CLEAN\_NKEEP** parameter preferentially, combined with a

`CLEAN_STOP = r SIGMA` with `r` between 1 or 2. That keeps `CLEAN_ARES`, `CLEAN_FRES` and `CLEAN_NITER` to zero. If it does not work, then

- Estimate an empirical noise on your first deconvolved cleaned image with `STATISTIC`, `CLEAN`, or `SHOW NOISE`.
- If this empirical noise value is similar to the value computed from the visibility weights (this noise value is one of the outputs of the `UV_MAP` command), your observation is not dynamic range limited. Apart from using a user-specified support (`SUPPORT` or `MASK`) there is not much you can do to improve your result,
- If not, you are dynamic range limited. You may use `CLEAN_STOP = r %` where `r` depends on the dynamic range as stopping criterium. Alternatively, you can select the effective noise level as the true Sigma, `CLEAN_STOP = r 'clean%rms'` with `r` being 1 to 2. The problem in such cases is that the noise level may be channel dependent, an issue that is not well handled.

**Convergence checks** Ensure that your deconvolution converged by checking that:

- The cumulative flux as a function of the number of clean component has reached a roughly constant level (use `/FLUX` option of the deconvolution commands to see this curves, or `SHOW CCT` or `VIEW CCT`).
- The residuals are similar or smaller in the source region (where Clean components were found) compared to elsewhere.

If not, change the values of the stopping criterion, whichever you used.

**Deconvolution methods** If you want a robust result in all cases, start with `HOGBOM`. If you prefer obtaining a quick result, use `CLARK` but you then first need to check that the dirty sidelobes are not too large on the dirty beam. If you obtain stripes in your Clean image:

- First check that your deconvolution converged.
- Then check that there is no spurious visibilities that should be flagged : use command `UV_FLAG` as a last resort.
- If it is clear that you have an extended source structure, you should first ask yourself whether you are in the wide-field imaging case and act accordingly (see next chapter). Else you can try a `CLEAN` variant which better deals with cases that implies a large spatial dynamic. This is rare at NOEMA, but may happen with ALMA.

**Outside help** Always consult an expert until you become one.

## 7 Wide-field imaging and deconvolution

We are often asked why the wide-field imaging and deconvolution steps are more difficult than their equivalent for single-field. The main answer is that doing wide-field observations with an interferometer is kind of paradoxical. Indeed, (sub)millimeter interferometers are before all tuned to get the best possible spatial resolution. A natural consequence is the lack of measurement of the low spatial frequencies which are extremely important in wide-field observations. Hence the paradox.

Progress in the design (ALMA was designed with wide-field imaging as a main goal) or in performances (NOEMA and the 30-m) has led to wide-field images being now customary. The tools have become much simpler and user-friendly (see below !) but because of its paradoxical nature, wide-field imaging with an interferometer implies a knowledgeable use of those tools.

### 7.1 In a nutshell

```
1 read uv gag_demo:demo-mosaic-imager.uvt
(2) read single gag_demo:demo-single-imager.tab
(3) uv_short
4 uv_map
5 clean
(6) fit /jvm; uv_restore
7 show sky
8 write * MyDemo
```

1. Read your *uv* data
2. Optionally, read your single-dish data
3. Optionally, merge it with the *uv* data set, by using the single-dish data to provide short spacings for the interferometer data.
4. Image as usual
5. deconvolve as usual
6. Optionally, improve result by refining the residuals
7. look at it
8. Save the result.

You are done. If the *uv* data set is a **Mosaic** data set, it works as if it is a single-field, except that the result appears as the **SKY** brightness distribution, because it is always corrected for primary beams.

Now, if the result is crazy, do not blame the software. Rather read carefully the information below: **Mosaics** and **UV\_SHORT** are simple to use, but can be tricky to use well !...

### 7.2 General considerations about wide-field imaging

The measurement equation for a millimeter interferometer is to a good approximation (after calibration)

$$V(u, v) = \text{FT} \{ B_{\text{primary}} \cdot I_{\text{source}} \} (u, v) + N \quad (7)$$

where  $\text{FT} \{ F \} (f)$  is the bi-dimensional Fourier transform of the function  $F$  taken at the spatial frequency  $f$ ,  $I_{\text{source}}$  the sky intensity,  $B_{\text{primary}}$  the primary beam of the interferometer (*i.e.* a

Gaussian of FWHM the natural resolution of the single-dish antenna composing the interferometer),  $N$  some thermal noise and  $V(u, v)$  the calibrated visibility at the spatial frequency  $u, v$ . The product of the sky intensity by the primary beam, which “quickly” decreases to zero, implies that an interferometer looking at a particular direction of the sky will have its field-of-view limited by the size of the primary beam.

To image a field-of-view larger than the primary beam size, the antennae of an interferometer will be successively pointed in different directions of the sky typically separated by half the size of the primary beam. This process is called mosaicing and the result requires specific imaging and deconvolution steps. Another possibility is to acquire data as the interferometer antenna continuously slew through a portion of the sky. This second observing mode is called interferometric On-The-Fly (OTF). While mosaicing is standard at NOEMA (see section 7.3), some efforts are currently done to commission the OTF observing mode.

Mosaicing and OTF clearly belongs to wide-field imaging. However considerations about wide-field imaging start as soon as the size of the source is larger than about  $1/3$  to  $1/2$  of the interferometer primary beam. Indeed, a multiplicative interferometer (*e.g.* all interferometer in the (sub)mm range) is a bandpass instrument, *i.e.* it filters not only the large spatial frequencies (this is the effect of the finite resolution of the instrument) but also the small spatial frequencies (all the frequencies smaller than typically the diameter of the interferometer antennas). An important consequence is that a multiplicative interferometer do *not* measure the total flux of the observed source. This derives immediately from the following property of the Fourier Transform: The Fourier transform of a function evaluated at zero spacial frequency is equal to the integral of your function. Adapting this to our notation, this gives

$$V(u = 0, v = 0) \stackrel{\text{FT}}{=} \sum_{ij \in \text{image}} \{B_{\text{primary}} \cdot I_{\text{source}}\}_{ij}. \quad (8)$$

*i.e.* the visibility at the center of the  $uv$  plane is the total intensity of the source. As a multiplicative interferometer filters out in particular  $V(u = 0, v = 0)$ , the information about the total flux of the observed source is lost. In summary, a multiplicative interferometer only gives information about the way the flux of the source is distributed in the spatial frequencies larger than the primary beam but no information about the total flux.

Deconvolution algorithms use, in one way or another, the information of the flux at the smallest *measured* spatial frequencies to extrapolate the total flux of the source. This works correctly when the size of the source is small compared to the primary beam of the interferometer. The extreme case is a point source at the phase center for which the amplitude of all the visibilities is constant and equal to the total flux of the source: Extrapolation is then exact. However, the larger the size of the source, the worst the extrapolation, which then underestimates the total source flux. This is the well-known problem of the missing flux that observers sometimes note when comparing the flux of the source delivered by a mm interferometer with the flux observed with a single-dish antenna. The transition between right and wrong extrapolation is not well documented. It depends on the repartition of the flux with spatial frequencies but also of the signal-to-noise ratio of the measured spatial frequencies. It is often agreed that the transition happens for sizes between  $1/3$  and  $1/2$  of the interferometer primary beam. For larger source size, information from a single-dish telescope is needed to fill in the missing information and to thus obtain a correct result. This is the object of section 8.

### 7.3 Mosaicing

#### 7.3.1 Observations and processing

In a single-field observation, an interferometer tracks a particular direction of the sky, named the phase center. The portion of the sky which can be image around this direction is directly linked to the size of the primary beam. The easiest way to image field-of-view larger than the primary beam size is to track one direction of the sky after another until the desired field-of-view is filled with small images made around many different tracking directions. This observing mode is called mosaicing and the tracked observations which constitute the mosaic are called fields.

There are many constraints to optimize mosaicing.

**Nyquist sampling of the mosaic field-of-view and mosaic pattern** The mosaic field-of-view must at least be Nyquist-sampled to obtain a reliable image. Each observed field can produce a reliable image of the same shape than the primary beam, *i.e.* a circular Gaussian (This assumes that the short-spacing problem has been solved). Nyquist sampling thus implies that the mosaic fields follow an hexagonal compact pattern as this ensures a distance between all neighboring fields of half the primary beam size. When the total observing time is fixed, Nyquist sampling is the best compromise between sensitivity and total field-of-view. Indeed, the distance between neighboring fields could be less (in which case the mosaic would be oversampled) than half the primary beam size. In this case, the sensitivity on each pixel of the final image would increase with the share of the time spent to observe this direction.

**Uniform imaging properties and quick loop around the fields** Getting uniform imaging properties is a desirable feature in the final result. This implies that a  $uv$  coverage and a noise level as uniform as possible among the different fields. Quickly looping around the different fields is the easiest way to reach this goal. However, dead time to travel from one field to another must almost be minimized. At NOEMA, the compromise is to pause at least 1 minute on each field and to try to loop over all the fields between two calibrations every 20 minutes. Hence, mosaic done in a single observing run is made of at most 20 fields. Larger mosaic must be observed by group of fields in different observing runs.

#### 7.3.2 Imaging

When combining together (dirty or clean) images, it is important to correct the primary beam attenuation to avoid modulation of the signal in the combined image. If we forget for the moment the dirty beam convolution, the images associated to each fields are noisy measurement of the same quantity (the sky brightness distribution) weighted by the primary beam. The best estimation of the measured quantity is thus given by the least mean square formula

$$M(\alpha, \delta) = \frac{\sum_i \frac{B_i(\alpha, \delta)}{\sigma_i^2} F_i(\alpha, \delta)}{\sum_i \frac{B_i(\alpha, \delta)^2}{\sigma_i^2}}, \quad (9)$$

where  $M(\alpha, \delta)$  is the brightness of the dirty/cleaned mosaic image in the direction  $(\alpha, \delta)$ ,  $B_i$  are the response functions of the primary antenna beams in the tracking direction of field  $i$ ,  $F_i$  are the brightness distributions of the individual dirty/cleaned maps, and  $\sigma_i$  are the corresponding noise values. As may be seen on this equation, the intensity distribution of the mosaic is corrected for

primary beam attenuation. This implies that noise is inhomogeneous. Indeed, if  $N(\alpha, \delta)$  is the noise distribution and  $\sigma(\alpha, \beta)$  is its standard deviation in the direction  $(\alpha, \beta)$ , we have

$$N(\alpha, \delta) = \frac{\sum_i \frac{B_i(\alpha, \delta)}{\sigma_i^2} N_i(\alpha, \delta)}{\sum_i \frac{B_i(\alpha, \delta)^2}{\sigma_i^2}}, \quad (10)$$

and

$$\sigma(\alpha, \delta) = \frac{\sqrt{\sum_i \frac{B_i(\alpha, \delta)}{\sigma_i^2}}}{\sum_i \frac{B_i(\alpha, \delta)^2}{\sigma_i^2}} = \frac{1}{\sqrt{\sum_i \frac{B_i(\alpha, \delta)^2}{\sigma_i^2}}} \quad (11)$$

Not only, the noise strongly increases near the edges of the mosaic field-of-view. But also, the center of each field is contaminated by increased noise level coming from the external regions of the neighboring fields. Indeed, the noise corrected for the primary beam attenuation is largely increasing where the primary beam is going to zero. To limit these effects, both the primary beams used in the above formula and the resulting mosaic are truncated.

### 7.3.3 Deconvolution

Standard CLEAN algorithms must be slightly modified to work on a dirty mosaics. Indeed, the use of truncated primary beam in the above equations is only a first order measure to avoid noise artifacts. However, the noise level still increases at the edges of the mosaic, implying that at some point the CLEAN algorithms will confuse noise peaks at the mosaic edges with true signal. To avoid this, the iterative search is made on a signal-to-noise image  $M(\alpha, \beta)/\sigma(\alpha, \beta)$  instead of the residual image. At the restoration step, the clean component list is used to produce the residual map and clean map. Nothing particular is done with the remaining signal-to-noise image.

### 7.3.4 Typical use

The processing of mosaics for NOEMA is essentially similar to that of single fields. There are only two small changes

**Creation of *uv* table** A mosaic UV table should be created using the **/MOSAIC** option of command **TABLE** in **CLIC**.

**Imaging** is done through **UV\_MAP** as for a single field. However, the process is different. The command takes into account the various fields, the primary beams, and select an optimum projection center (phase center). The later may need to be specified by the user using the **MAP\_CENTER** string, or as argument to **UV\_MAP**

**Deconvolution** is also similar, but not all algorithms are available: **MX**, **SDI** and **MRC** do not work for mosaics. The change of behavior of the CLEAN algorithms is visualized through the change of prompt from **IMAGER>** to **MOSAIC>**. Two additional variables are used for mosaic deconvolution

**CLEAN\_SEARCH** The minimum fraction of a primary beam below which no Clean component is searched for.

**CLEAN\_TRUNCATE** The minimum fraction of a primary beam cumulated response below which no image restoration is performed. Below this threshold, the Clean image is blanked.



Finally, note that the mosaic deconvolution produces sky brightness images (**SKY** variable) while single-field deconvolution produces images attenuated by the primary beam.

**IMAGER** makes no specific assumption about the *uv* coverage of individual fields. However, it uses a single Clean beam in the deconvolution, so Mosaics where fields have widely different *uv* coverage will not conserve flux properly. Mosaicing deconvolution will work better if all fields are equivalent in *uv* coverage and noise level.

A mosaicing session would thus just be like a single-field imaging:

```
1 read uv gag_demo:demo-mosaic
2 uv_map
3 hogbom /flux 0 10
4 fit /jvm
5 uv_restore
6 show sky
7 write * demo
```

Comments:

**Step 1** Read the UV table

**Step 2** Image the mosaic

**Step 3** Deconvolve

Step 4-5 Optimize residuals (see Sec.7.4)

**Step 6** Look at the result. The result is in **SKY**.

**Steps 7** Save the result **SKY**, and the intermediate files (**BEAM**, **DIRTY**, **PRIMARY**).

However, mosaics can be huge and require more memory than available (see Section 14) To overcome this issue, **IMAGER** provides the script @ **image-mosaic** that splits the **UV\_MAP** step into slices that fit into memory. The user can then read the resulting images and deconvolve them, eventually by blocks of channels if needed (in particular when a **uv\_restore** step is desired) using a similar logic.

## 7.4 Mosaic and JvM factor

By construction, the various fields covered in a mosaic have different *uv* coverages, and thus different synthesized beams. Furthermore, mosaic covers wider fields, so the impact of frequency variable angular resolution is more important than in single fields.

Yet, the mosaic is restored with a unique Clean beam. This situation leads to a mismatch between the use Clean beam and the dirty beams in some or even most of the fields. Furthermore, because Mosaics often use short spacings (see Section 8), the dirty beams often present a wide “plateau” that is not well fit by a Gaussian Clean beam. These are situations which are prone to lead to inaccurate large scale flux restoration, because the Clean beam and dirty beams area do not match.

To minimize these issues, it is recommended in **IMAGER** to use the **FIT /JVM\_FACTOR** and **UV\_RESTORE** commands that correct this mismatch to first order by re-scaling the residual by the Clean to Dirty beam ratio, the so-called **JvM factor** (Jorsater & van Moorsel (1995)). Only do so once you are satisfied with your deconvolution, as **UV\_RESTORE** is often time consuming on Mosaics.

## 8 Short and Zero spacings

### 8.1 In a nutshell

```

1 read uv gag_demo:demo-mosaic-imager.uvt
2 read single gag_demo:demo-single-imager.tab
3 uv_short
4 uv_map; clean
5 view clean
6 write * MyDemo

```

1. Read your *uv* data
2. read your single-dish data
3. Merge it with with the *uv* data set,
4. Image and deconvolve as usual
5. check the result. You can use CLEAN as argument to **SHOW** or **VIEW: IMAGER** will automatically fall back to **SKY** if needed (and vice versa).
6. Save it.

You are done. This works for mosaics as well as single fields.

But, again, if the result are crazy, do not blame the software. Rather read carefully the information below: **UV\_SHORT** is simple to use, but can be tricky to use well !...

### 8.2 Principle

Let us note  $D$  the diameter of the single-dish antenna ( $D = 30\text{m}$  for the IRAM-30m telescope) used to produce the short-spacing information and  $d$  the diameter of the interferometer antennas ( $d = 15\text{m}$  for NOEMA). We already mentioned that a multiplicative interferometer filters out all the spatial frequencies smaller than  $\sim d$  meters. When this information is needed to get reliable results, the source should also be observed with a single-dish antenna to produce the missing information. The single-dish antenna furnishes information about all spatial frequencies up to  $\sim D$  meters (but this information is weighted by the single-dish beam shape, *i.e.* high frequencies are measured with a worse signal-to-noise ratio than low frequencies). To recover all the information at spatial frequencies smaller than  $d$  meters, the diameter of single-dish antenna must be larger or equal to the diameter of the interferometer antennae:  $D \geq d$ .

### 8.3 Algorithms to merge single-dish and interferometer information

The measurement equations of a single-dish and an interferometer are quite different from each other. Indeed, the measurement equation of a single-dish antenna is

$$I_{\text{meas}}^{\text{sd}} = B_{\text{sd}} \star I_{\text{source}} + N, \quad (12)$$

*i.e.* the measured intensity ( $I_{\text{meas}}^{\text{sd}}$ ) is the convolution of the source intensity distribution ( $I_{\text{source}}$ ) by the single-dish beam ( $B_{\text{sd}}$ ) plus some thermal noise, while the measurement equation of an interferometer can be rewritten as

$$I_{\text{meas}}^{\text{id}} = B_{\text{dirty}} \star \{B_{\text{primary}} \cdot I_{\text{source}}\} + N, \quad (13)$$

*i.e.* the measured intensity ( $I_{\text{meas}}^{\text{id}}$ ) is the convolution of the source intensity distribution times the primary beam ( $B_{\text{primary}} \cdot I_{\text{source}}$ ) by the dirty beam ( $B_{\text{dirty}}$ ) plus some thermal noise.  $B_{\text{sd}}$  has very similar properties than  $B_{\text{primary}}$  and very different properties than  $B_{\text{dirty}}$ . In radioastronomy,  $B_{\text{sd}}$  and  $B_{\text{primary}}$  both have (approximately) Gaussian shapes. Moreover, the fact that we will use the single-dish information to produce the short-spacing information filtered out by the interferometer implies that  $B_{\text{sd}}$  and  $B_{\text{primary}}$  have similar full width at half maximum. Now,  $B_{\text{dirty}}$  is quite far from a Gaussian shape with the current generation of interferometer (in particular, it has large sidelobes) and the primary side lobe of  $B_{\text{dirty}}$  has a full width at half maximum close to the interferometer resolution, *i.e.* much smaller than the FWHM of  $B_{\text{sd}}$ .

Merging both kinds of information obtained from such different measurement equations thus asks for a dedicated processing. There are mainly two families of short-spacing processing: the **hybridization** and the **pseudo-visibility** techniques.

### 8.3.1 Hybridization technique (“feathering”)

In this family, most of the processing is done on the interferometric data alone. Indeed, the interferometric data is deconvolved and corrected for the primary beam contribution to obtain

$$I_{\text{sky}}^{\text{id}} = B_{\text{clean}} \star I_{\text{source}} + N', \quad (14)$$

where  $B_{\text{clean}}$  is a Gaussian of FWHM equal to the interferometer resolution and  $N'$  is some thermal noise corrected for the primary beam contribution. Two main facts are hidden in this formulation: 1) the field-of-view of the observation is obviously limited to the observed portion of the sky and 2) more importantly, the lack of short-spacings has not yet been overcome and a better formulation would be

$$I_{\text{sky}}^{\text{id}} = \text{Highpass-filter} \{B_{\text{clean}} \star I_{\text{source}}\} + N'. \quad (15)$$

The simplicity of equation 14 is thus slightly misleading but we will keep it for the sake of simplicity. The hybridization method consists in combining two images ( $I_{\text{meas}}^{\text{sd}}$  and  $I_{\text{clean}}^{\text{id}}$ ) in the  $uv$  plane.

1. Both images are first spatially regridded on the same fine grid.
2. The FFT of those two images are computed, and linearly combined by selecting the low spatial frequencies from  $\text{FFT}(I_{\text{meas}}^{\text{sd}})$  and the high spatial frequencies from  $\text{FFT}(I_{\text{sky}}^{\text{id}})$ .

$$\text{FFT}(uv) = f(uv)\text{FFT}(I_{\text{meas}}^{\text{sd}}) + (1 - f(uv))\text{FFT}(I_{\text{sky}}^{\text{id}})$$

The transition  $f(uv)$  between low and high spatial frequency is selected to use the best regions of the  $uv$  plane in both images.

3. The result is FFTed back to the image plane to produce a final, unique image, which takes into account both single-dish and interferometric information.

The method has the following free parameters: the transition radius and the detailed shape of that transition. To avoid discontinuity, the transition shape is chosen to be reasonably smooth. When the low resolution image is provided by a single-dish, the best signal-to-noise combination is obtained using a function  $f(uv)$  that is Fourier transform of the single-dish beam. However, that is only optimal if the noise in this image is small enough and no other instrumental effect

(such as pointing errors or baseline ripples) affect the data. So,  $f(uv)$  can also be chosen arbitrarily. The spatial frequency of transition is selected close to the smallest spatial frequency reliably measured by the interferometer (*e.g.* about 18 m for NOEMA), and/or the largest spatial frequency measured by the low resolution image (*e.g.* about 20 m for data taken with the IRAM 30-m telescope). For combining ACA and ALMA data, this would be 15 m, and of ACA and 12-m single dish, about 9 m.

### 8.3.2 Pseudo-visibility technique

**General description** In this family, the single-dish information is heavily processed before merging with the interferometric information. The basic idea is to produce from the single-dish observations pseudo-visibilitys similar to the ones that would be produced by the interferometer if they were not filtered out.

1. The Single-Dish measurements are re-gridded and then FFTed into the  $uv$  plane.
2. The data are deconvolved of the single-dish beam ( $B_{sd}$ ) convolution by division by its Fourier Transform (truncated to the antenna diameter).
3. The data are FFTed back to the image plane and multiplied by the interferometer primary beam,  $B_{primary}$ .
4. The result is FFTed again in the  $uv$  plane where the visibilitys are sampled on a regular grid.
5. In the case of a mosaic, the two last operations are performed for each pointing center.

Using the properties of the Fourier transform, we can rewrite the measurement equation of an interferometer as

$$V(u, v) = \{FT(B_{primary}) \star FT(I_{source})\}(u, v) + N. \quad (16)$$

This equation means that the visibility measured by an interferometer at the spatial frequency  $(u, v)$  is the convolution of the Fourier transform of the source intensity distribution by the Fourier transform of the primary beam. Hence, to get pseudo-visibilitys truly consistent with interferometric visibilitys, we must be able to reliably compute the convolution by the Fourier transform of the primary beam. This implies that we can compute pseudo-visibilitys only for spatial frequencies lower than  $D-d$ . The use of the IRAM-30m to produce the short-spacing information of the NOEMA is thus ideal as it enables to recover pseudo-visibilitys up to 15 m (=30 m-15 m). Once the pseudo-visibilitys have been computed, they are merged with the interferometric visibilitys and standard imaging and deconvolution are then applied to the merged data set.

**Single-dish vs interferometer weight** In all cases involving short spacings, the relative weight of the single dish data to interferometer data is critical. Within the restrictions imposed by the noise level, this relative weight is a free parameter. It is all the more important that the Fourier transform of the  $uv$  plane density of weights is the dirty beam, a key parameter of the deconvolution. The general goal is to have a dirty beam as close as possible to a Gaussian. As the Fourier transform of a Gaussian is a Gaussian, we search for obtaining a  $uv$  plane density of weights as close as possible to a Gaussian. In general, the short spacing frequencies are small compared to the largest spatial frequency measured by an interferometer. This implies we can use the linear approximation of a Gaussian, *i.e.* a constant, in the range of frequencies used for the short spacing processing. We thus end up with the need to match (as far as possible) the

Single-Dish and interferometric densities of weights in the  $uv$  plane. In practice, we compute the density of weights from the single-dish in a  $uv$  circle of radius  $1.25 d$  and we match it to the averaged density of weights from the interferometer in a  $uv$  ring between  $1.25$  and  $2.5 d$ . Experience shows that this gives the right order of magnitude for the relative weight and that a large range of relative weight around this value gives very similar final results.

When processing IRAM-30m data to combine to NOEMA data, this criterion implies a large down-weighting of the IRAM-30m data which may make think that too much observing time was used at the IRAM-30m data. However, just using the above criterion to determine the observing time needed at the IRAM-30m would in general lead to very low signal-to-noise ratio of the single-dish map. In such a case, it is very difficult to detect problems which would translate in strong artifacts in the IRAM-30m + NOEMA combination. We recommend to ask for enough IRAM-30m time to get a *median* signal-to-noise ratio of 5 on the single-dish map. This ratio should be achieved for all velocity channels of interest (which may include the line wings).

### 8.3.3 Comparison

The simplicity of the hybridization technique is its main advantage. It is simple to understand and simple to implement. However, this method works badly in practice because it is truly difficult to obtain a reliable deconvolution of interferometric data alone when short-spacing information is important. An interferometer is a spatial pass-band filter, filtering in particular the zero spacing. This implies that the total flux in the dirty image is zero (*i.e.* as much negative as positive flux in the dirty image) but that the dirty beam integral is also zero (*i.e.* as much negative as positive sidelobes). Adding the short-spacing information (and in particular the zero spacing) through the pseudo-visibility method, we enforces the positivity of the dirty image total flux and of the dirty beam integral. It is well-known that trying to deconvolve a mosaic built only with interferometric data is quite difficult. It almost always requires the definition of support where the CLEAN algorithms can search for clean components with the clear risk to bias the final result. In contrast, adding the short-spacing information through pseudo-visibility enables an almost straightforward CLEAN deconvolution *without* the need of any support.

For the sake of illustration, let us assume an intensity distribution made of a large scale structure (*e.g.* a smoothly varying intensity) superimposed with a small scale distribution both in emission and absorption. An interferometer will filter out the smooth distribution. If there is no additional zero spacing information, the smooth distribution is completely lost with the important consequence that the final deconvolved image will have positive (emission) and negative (absorption) structures. Trying to reproduce both negative and positive structures is one of the most difficult task for deconvolution algorithms. In addition, the presence of large negative structures create instabilities in the algorithms of the CLEAN family (because it is difficult to distinguish between negative absorption structures and negative sidelobes of emission structures). Only the definition of support around positive emission peaks may succeed to stabilize the CLEAN algorithms with the drawback of biasing the result.

Both kind of algorithms are implemented in **IMAGER**, under commands **FEATHER** for the hybridization and **UV\_SHORT** for the pseudo-visibility. However, we strongly recommend to use the pseudo-visibility algorithm. Pety et al. (2001a,b,c) showed through simulations that 1) the pseudo-visibility algorithm implemented in GILDAS enable extremely reliable results (fidelities of a few thousands) on ideal observations and 2) the accuracy of the wide-field imaging is limited by pointing errors, amplitude calibration errors and atmospheric phase noise (and not by the used algorithms), even for ALMA.

## 8.4 Hybridization technique and ALMA

A special case where Hybridization can be extremely useful is that of ALMA observations involving the main 12-m array, the ACA and single-dish data with the 12-m antennas. These can be combined in several ways.

For example, the deconvolved mosaic made (using the pseudo-visibility method) from ACA and the single-dish data can be used as a single-dish image, providing short spacings that complete (either as pseudo-visibilitys, or by feathering) the 12-m data.

In most circumstances, an optimal result is obtained by hybridizing Cleaned images produced from the mosaics obtained by combining (using the pseudo-visibility method) ACA and Single-dish data as short spacings, with another mosaic obtained with the 12-m data and the Single-dish data (as zero spacing in this case) together.

The deconvolution of each mosaic is stabilized by the addition of the 12-m single-dish zero or short spacings, and these good mosaics are then merged in an optimal way by using the best region of the  $uv$  plane that they sample, typically using a transition radius of 15 to 18 m.

See command **FEATHER** for details.

## 8.5 The Zero spacing: an important subset

An important subset of the pseudo-visibility method is the production of only the zero spacing. Indeed, the zero spacing is just the total flux of the observed field-of-view. Hence, if the observed field-of-view is small enough to fit in the single-dish beam (this is in particular always the case if  $D = d$ ), a single spectrum observed with the single-dish telescope in the direction of the interferometer phase center may be used as zero spacing, only a scaling from Kelvin to Jansky is needed. This is the poor man solution as only part of the short spacing information is recovered by this technique.

## 8.6 Short Spacings in practice: command UV\_SHORT

Our algorithm to produce the short-spacing information is coded in the **UV\_SHORT** command. **UV\_SHORT** will **add** the short spacing information to the current  $uv$  table (read by command **READ UV** and optionally transformed by further **UV...** processing commands).

**UV\_SHORT** has a substantial number (17) of control variables, but with experience, they have been reduced to 5 significant ones, among which only 3 really matter in most cases but often can be used with their default values:

**SHORT\_SD\_FACTOR** The single-dish brightness unit to flux conversion factor. If set to zero, **UV\_SHORT** will attempt to derive it from the information available in the single-dish data

**SHORT\_UV\_TRUNC** The longest baseline retained in the pseudo-visibilitys. It defaults to the maximum theoretically possible, the single-dish diameter minus the interferometer diameter. Smaller values are allowed, and even recommended if the pointing quality of the single-dish data is moderate.

**SHORT\_SD\_WEIGHT** The relative weight scaling factor between the pseudo-visibilitys and the interferometer visibilitys.

The relative weight of these visibilitys is derived by **UV\_SHORT** in order to optimize the shape of the overall synthesized beam. **SHORT\_SD\_WEIGHT** is a scale factor to this optimum weight, which may need to differ from 1 in case of poor  $uv$  coverage in the interferometer data or noisy single-dish data (it should be lower than 1 in this case).

**UV\_SHORT ?** will list these 3 major ones, and **UV\_SHORT ??** the 2 remaining main ones:

**SHORT\_TOLE** The position tolerance in the single-dish map

**SHORT\_MIN\_WEIGHT** The minimum (relative) weight for a spectrum in the single-dish map to be included.

as well as four optional ones needed only if the original single-dish and *uv* data lacks the proper information (antenna diameter and beam sizes)

The **UV\_SHORT** command starts from data in a the format produced by the **CLASS** command **TABLE** command, and read in **IMAGER** through command **READ SINGLE**. Basically, this is a GDF table containing one line per spectrum, the columns representing the lambda offset, beta offset, weight, and the spectrum intensities.<sup>6</sup> This data must match spectrally the velocity sampling of the interferometric data. This can be obtained using the **/RESAMPLING** option of command **TABLE** in **CLASS**.

The **READ SINGLE** and **UV\_SHORT** commands also support a 3-D data cube (as produced by e.g. command **XY\_MAP** in **CLASS**) as input instead of a **CLASS** table. Again, the velocity axis must match that of the interferometric data.

**UV\_SHORT** will automatically produce the Zero spacing from the single-dish data when the data does not allow other short spacings to be evaluated. The temporary image produced by **UV\_SHORT** when starting from a **CLASS** Table is stored in the **SHORT** buffer, and can be written by command **WRITE**. This image can also be computed separately by command **XY\_SHORT**.

Finally, as **UV\_SHORT** adds the short spacing information, **UV\_SHORT /REMOVE** allows to remove it (there is no direct “replace” possibility because the *uv* sampling may change).

## 8.7 Practical considerations

### 8.7.1 When are short-spacing information needed?

- If the source size is smaller than 1/3 the primary beam size, short-spacing information is superfluous.
- If the source size is between 1/3 and 1/2 the primary beam size of NOEMA antennas, a single spectra obtained at the IRAM-30m telescope in the direction of the source can be used to produce the zero spacing information with the **UV\_SHORT** command. Indeed, the IRAM-30m diameter being twice the diameter of the NOEMA antenna, all the flux of the source will be measured by a single IRAM-30m spectrum only if the size of the source is smaller than 1/2 the primary beam size of NOEMA antennae.
- If the source size is larger than 1/2 the primary beam size of NOEMA antennas, short-spacing information under the form of an IRAM-30m map is almost always mandatory. The only exception could be wide-field imaging of a region made of unresolved or small (compared to the primary beam size) sources as it may happen when mapping close-by external galaxies for instance. However, adding short-spacing will anyway help the deconvolution.
- Short-spacing information is only useful if the brightness of the extended component is above the noise level. This requires a prior knowledge of the total flux in the imaged

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<sup>6</sup>This format is subject to change: Please, refer to the **TABLE** documentation for up-to-date information

area to be determined. However, this information may be available from previous low-sensitivity single-dish observations. Checking this can avoid wasting a lot of telescope (and astronomer) time.

A generalization to ALMA (12 m antenna) and ACA (7 m antennas) is straightforward.

### 8.7.2 How to optimize single-dish observations?

One of the main difficulty of the short-spacing problematic is the need of observations from a single-dish telescope at least as big as the interferometer antennas<sup>7</sup>. In this respect, the IRAM-30m and NOEMA are very complementary. Nevertheless, when observing with the single-dish telescope, a few precautions are needed to avoid contaminating the interferometric data with possible artifacts of single-dish data.

- The field-of-view of the single-dish map must be twice the field-of-view covered by the mosaic. The only exception to this rule happens when the source intensity decreases to zero in a smaller field-of-view. Indeed, there is no point in observing an empty sky.
- The observing strategy must enforce Nyquist sampling (or better) of the source at the resolution of the single-dish telescope.
- A particular care should be taken of the pointing, tracking and amplitude calibration and baseline removal as those are critical issues in obtaining a high quality single-dish map to produce short-spacing information. For instance, data with too large tracking errors should be discarded.
- Among “baseline” issues, the presence of continuum sources is to be treated with care. Continuum is difficult to measure with single-dish telescopes, and a (linear or polynomial) spectral baseline is often fitted to avoid atmospheric contamination. In such cases, the combination should be made with interferometer data where the continuum has been removed, and added back later...
- We advise to make many On-The-Fly coverages of the observed field-of-view to get homogeneous observing conditions. Scanning in perpendicular directions is needed to decrease stripping.

Sometimes, single-dish telescope time is scarce and some of the above criteria can not be fulfilled. In those cases, you can still try to use your single-dish observations and our algorithm will try to make its best to get a sensible result. However, any artifact in the combination may directly come from wrong single-dish observations. In other words, do *not* blame the software unless you are sure of the quality of the quality of your single-dish (and interferometric) observations...

---

<sup>7</sup>If there were no pointing errors, a single-dish of the same size as the interferometer antennas would be strictly sufficient.



## 9 Self Calibration

### 9.1 Self-Calibration in a nutshell

```

1 read uv YourData
2 selfcal phase
3 selfcal summary
4 selfcal show
5 selfcal apply
6 uv_map
7 clean
6 write * YourSelf

```

1. Read your *uv* data
2. Self-calibrate the phase
3. Get a summary of the result
4. Show the phase correction between the last 2 iterations
5. Apply the self-calibration
6. Image as usual
7. Clean as usual
8. Save the result if it is worthwhile...

You are done. But, now, if the result is crazy, do not blame the software. Rather read carefully the information below: **SELF CAL** is simple to use, but there are some pitfalls...

### 9.2 Self-Calibration Principle

The self-calibration idea is based on the fact that the dominant error terms are antenna-based, while source information is baseline-based. With  $N$  antennas, one gets at any time  $N(N - 1)/2$  visibility measurements, but  $N$  amplitude gains, and only  $N - 1$  error terms for the morphology of the source (phase gains). The  $N - 1$  number is because only relative phases count. The absolute flux scale is a separate problem, and therefore also  $N - 1$  relative amplitude gains count.

The measured visibilities on baselines from antenna  $i$  to antenna  $j$  at time  $t$  are, from the simplified measurement equation:

$$V_{\text{obs}}(i, j, t) = G(i, t)G^*(j, t)V_{\text{true}}(i, j) + \text{Noise} \quad (17)$$

where  $G(i, t)$  is the complex (phase and amplitude) gain for the antenna  $i$  at time  $t$ . The true visibility  $V_{\text{true}}(i, j)$  only depends on the baseline  $(i, j)$ , not on the time.

Given a source model  $V_{\text{mod}}(i, j)$ , one can derive the antenna gain products at time  $t$ , based on the system:

$$\frac{V_{\text{obs}}(i, j, t)}{V_{\text{mod}}(i, j)} = G(i, t)G^*(j, t) \quad (18)$$

which is an over-constrained process, since there are  $N(N - 1)/2$  constraints for  $N - 1$  unknowns. Solving for this over-constrained problem is similar to deriving the amplitude and phase solution from a calibrator observation. In the calibrator case (i.e., an unresolved source like a distant

bright quasar),  $V_{\text{mod}(i,j)} = (1.0, 0.0)$  (constant amplitude, zero phase), so there is no risk of noise amplification in the process.

For any (not a point-like) source,  $V_{\text{mod}}$  must be guessed. Self-calibration will use your source to improve the calibration of the antenna-based (complex) gains as a function of time. The practice is to proceed iteratively, based on a preliminary deconvolution solution. Let  $V_{\text{obs}}(k)$  be the “observed” visibilities at iteration  $k$ , with  $V_{\text{obs}(k=0)} = V_{\text{obs}}$  the raw calibrated visibilities. Some of the Clean components derived from  $V_{\text{obs}}(k)$  are used to define “model” visibilities  $V_{\text{mod}}(k)$ . Then, solving for the antenna gains, one obtains:

$$V_{\text{obs}}(k+1) = \frac{V_{\text{obs}}(k)}{(G_i G_j^*)} \quad (19)$$

The model is thus progressively refined, and in the end, satisfies better the initial constraints on the source shape and on the antenna gains as a function of time provided by the measurements. Note that the absolute phase (and hence the position) can be lost in the self-calibration process and it should not be used for absolute astrometry.

There are two types of self-calibration: phase and amplitude self-calibration. The amplitude gain is a more complex problem than the phase gain. Amplitude gains can (and often do) vary with time, but from the measurement equation, a scale factor in the amplitude gain can be exchanged by a scale factor on the source flux. It is thus customary to re-normalize the gains so that the source flux is conserved in the process. An alternate (perhaps not strictly equivalent) solution is to ensure that the time averaged product of the amplitude gains is 1. The two approaches differ by the averaging process.

For any typical source,  $V_{\text{mod}}$  is non zero and of magnitude smaller than 1 (using the total flux as a scale factor) since the source is partially resolved. So in computing  $V_{\text{obs}}/V_{\text{mod}}$ , there is noise amplification. It may even be the case that  $V_{\text{mod}}$  is zero (case of an extended, over-resolved emission), and thus some (long) baselines will yield no direct constraint on the antenna gains  $G(i)G^*(j)$ . But this should not matter too much for self-calibration, for two reasons. First, other (i.e., shorter) baselines may provide constraints on the gains. Second, if all  $V_{\text{obs}}$  for an antenna are close to zero, it implies  $V_{\text{mod}}$  must be close to zero too, so an error on the phase of those visibilities (as well as on its magnitude) is not so important.

Self-calibration is related to the “closure” relations. For any triplet of antennas, the phase of the triple product  $V_{ij}V_{jk}V_{ki}$  is independent of the antenna errors, and thus is (within the noise) a bias free constraint on the source. Similarly, for any quadruplet of antennas, the amplitude of the ratio  $(V_{ij}V_{kl})/(V_{ik}V_{jl})$  is independent of the antenna errors. But here, the noise amplification can be large because of the likelihood to have two small visibilities. For this reason, amplitude self-calibration requires in practice higher signal to noise ratios than phase calibration in the initial deconvolved data set used as a model.

Among the advantages of self-calibration, one may emphasize that antenna gains are derived at the correct time of the science object observation, while they must be interpolated in the classical calibration approach. Both atmospheric and electronic noises are supposed to vary with time, although with different timescales. Gains are also computed in the correct direction on the celestial sphere, while the calibrator-based approach introduces differences in the pointing direction with respect to the science object. The robustness of the approach increases with the number of baselines.

In order to implement self-calibration, it is however necessary that the signal to noise ratio be large enough (the process will require a sufficient bright source). Self-calibration can especially bring significant improvements to the calibration solution in the case of higher than expected

background noise, or in the presence of convolutional artifacts around objects, especially point sources.

### 9.3 Self-Calibration Implementation

The typical procedure for self-calibration consists in an iterative process based on the following steps:

1. **UV\_MAP /SELF + CLEAN + UV\_RESTORE /SELF:**  
from the classically calibrated (and preliminarily flagged) data, define an initial source model through a conservative (not too deep) first deconvolution : the model consists of a reasonably modest number of CLEAN components.
2. **SOLVE:** determine an estimate of the antenna gains (best fit to the observed visibilities)
3. **APPLY:** apply the derived gains to correct the observed data
4. **STATISTIC:** compare to the initial Image, and estimate the improvement through an adequate quality assessment (e.g., improvement of the dynamic range)
5. If necessary, re-build a new model from these corrected data, and iterate until the solution is satisfactory.

Phase-only self-calibration is less stringent on the signal-to-noise ratio (SNR) threshold than amplitude self-calibration, and it should therefore be attempted first. For phase self-calibration to work, the SNR values in the initial data should be at least of  $\text{SNR} > 3$  per antenna (in a solution interval shorter than the time for significant phase variations for all baselines to a single antenna). The SNR threshold in the initial image depends on the number of antennas and on the adopted time averaging. Depending on the complexity of the source (and the contribution from extended emission), all available baselines may not be considered in the process, and specific preliminary flagging could be necessary. Amplitude errors tend to be negligible for dynamic ranges below about 500. Amplitude self-calibration will thus be eventually attempted in a subsequent step.

Self Calibration is available in **IMAGER** through the command **SELF CAL**, which uses an iterative scheme driven by a script (**gag-pro:p.selfcal.ima**). From the above principle, the script controls

- a) the number of iterations
- b) the number of selected clean components at each iteration
- c) the time scale of the solution, i.e. the integration time over which the gains are assumed to be constant

The parameters of the command **SELF CAL** are available as **SELF\_Names** **SIC** variables. The script uses the commands **UV\_MAP**, **CLEAN**, and **SOLVE** and **APPLY** from the **CALIBRATE\** language. By default, a solution is searched for the phase calibration only (**SELF\_MODE=PHASE**), and the number of iterations is 3 (**SELF\_LOOP**). For each iteration:

- All components found by **CLEAN** are kept by default (**SELF\_NITER** = 0), but for simple source structures, 10 components only may be enough (the maximum number **NITER** of CLEAN components to subtract is automatically guessed by the program in the default process, see **CLEAN\_NITER** and other usual clean convergence control variables),
- the minimum flux density per pixel to be considered by CLEAN can be defined (**SELF\_MINFLUX** = 0)

- The "integration" times (gain averaging) are fixed to a default value `SELF_TIMES=45` s (minimum value for NOEMA, while it is only 6 s for ALMA). This can be adapted for each loop (in general, one should start with larger solution times, depending on the SNR values and try to decrease it in order to better sample the atmospheric fluctuations).

The number of iterations can be changed by resizing the `SELF_TIMES`, `SELF_NITER`, or `SELF_MINFLUX` arrays (the number of loops `SELF_LOOP` is then automatically recomputed). You should make sure that these 3 arrays have the same dimension. If any of the `SELF_NITER` and/or `SELF_MINFLUX` array are constant then their dimension is accordingly changed by `SELF CAL` each time one of these arrays is resized. For instance, the following command allows to define 5 loops with an integration time for solution of 45 sec:

```
let Self_times 45 45 45 45 45 /resize
```

`SELF_NITER` and `SELF_MINFLUX` are automatically enlarged to the same size if, and only if, they were already constant. By default, all channels are averaged to compute a "continuum" image, but the range of adequate channels can be specified through `SELF_CHANNEL`.

`SELF CAL PHASE` will compute a phase calibration, but will not apply it. One needs to call `SELF CAL` once more with the argument `APPLY` in order to apply the solution. The script really applies the solution if and only if the previously found solution can be considered as a good one (see `SELF_STATUS` argument value).

`SELF CAL APPLY` automatically saves the parameters and results in the *selfcal.last* file. By default, data are flagged if no sufficiently good solution is found. `SELF CAL APPLY` keep tracks of whether the solution has already been applied through `SELF_APPLIED`. `SELF CAL APPLY` will refuse to apply "bad" solutions: solutions are declared "bad" if the improvement in dynamic range and noise level is insufficient (i.e. below a precision level controlled by `SELF_PRECISION`). In this case, the `SELF_STATUS` variable is negative. In this case, the user can still decide to apply the solution directly using command `APPLY`, but the `SELF_APPLIED` variable will not be updated.

The merit criteria for the quality assessment of the computed solution are the final dynamic range, and the Clean map noise at each iteration. These quantities are stored in the `SELF_DYNAMIC` and `SELF_RMSCLEAN` variables (at each iteration). The dynamic is defined as the ratio of the peak flux density value to the noise in the clean map (automatically estimated with the command `STATISTIC`). The minimum signal to noise ratio value (for an antenna) for a valid solution is `SELF_SNR=6` by default.

`SELF CAL` can be controlled through a widget, using command `SELF CAL /WIDGET` (see Figure 1)

It is possible to visualize the computed corrections with the command `SELF CAL SHOW`. The solution computed with the `SOLVE` command is written in a *'self\_sname'.tab* file. By default, the difference between the last two iterations is displayed. For `PHASE`, the phase difference should be close to zero if the solution converged, and for `AMPLI` the amplitude values close to 1. It is also possible to show the difference between two specified iterations. In addition, the command `SELF CAL SUMMARY` will display the results of the process in terms of resulting noise and improved dynamic range. If the solution is satisfactory, the command `SELF CAL SAVE` can be used to save both the results and the parameters in the *selfcal.last* file. (`SELF CAL APPLY` performs an implicit `SELF CAL SAVE`.)

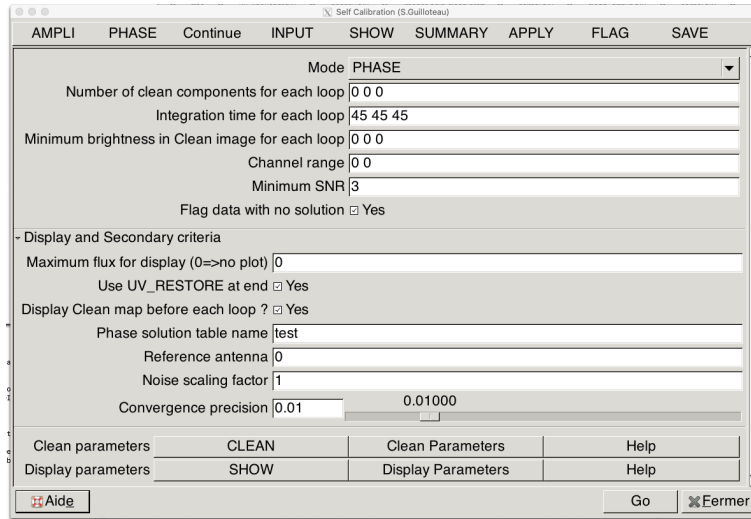


Figure 1: The Self-Calibration widget

## 9.4 Basic use

### 9.4.1 Timescale for averaging solution interval

The solution interval, or timescale used to average the solution for the gain variations, is the result of a tradeoff between the timescale of the true gain variations (e.g., changes in the atmospheric conditions or electronics) and the data averaging which is necessary to reach a minimum SNR value for the visibilities. In principle, this timescale should be smaller than the coherence time of the atmospheric fluctuations for the phase solution, typically one minute. It is in general longer for the amplitude gains, since here these are changes in the atmospheric transparency or antenna gains which matter. It is therefore recommended to start iterations with a not too short averaging time, and to decrease it in a second step if the self-calibration was successful. It is also recommended to use the same integration time for the last two iterations, in order to ease the interpretation of the results and of the **SELF CAL SHOW** display.

The current self-calibration method computes baseline-based gains (observed complex visibility divided by model prediction) for each visibility, and performs the time averaging on these baseline-based gains. Antenna based gains are derived from the time-averaged baseline-based gains. This is in principle an optimal method, since the model is not noisy: the linearity of the first step guarantees a noise decrease as square root of time.

### 9.4.2 Quality assessment and data flagging

**Validation of the solution** One of the difficulties of self-calibration is to evaluate whether it has improved the image or not. The self-calibration solution is biased towards the assumed model. If used with insufficient signal to noise, it will tend to produce a point source at the initial peak position, and the bias will be of order of the noise. This may be inappropriate. Currently, the validity of the self-calibration solution is based on the estimated signal to noise ratio for the gains at each time step. If that SNR is below a user-controlled threshold (by default, **SELF SNR=6**), the corresponding data is flagged (default value: **SELF FLAG=YES**) or kept WITHOUT self calibration (if **SELF FLAG=NO**).

**Flagging or not flagging ?** The decision to flag or not results from a trade-off:

- **SELF\_FLAG** = Yes : will result in no contamination by bad data, but may lead to lower angular resolution since long baselines may be flagged.
- **SELF\_FLAG** = No: will avoid loosing all long baselines (where the SNR is lower)

Both options may be explored, and it is recommended to check afterwards the final angular resolution with and without flagging.

The following scheme is proposed to check the validity of the self-calibration solution:

- read the status using **SELF CAL SUMMARY**
- use **SELF CAL SHOW** to verify if the solution is converged
- if it looks good, but noise is still far from theoretical, try again to self-calibrate with a shorter integration time (**SELF\_TIMES**).
- if it is not good, try to increase **SELF\_TIMES** and find an optimum value. For ALMA data, typical values may be in the range 6 – 60s, and for NOEMA in the range 45 – 120s. Alternatively, you can also try to decrease **SELF\_SNR** to lower values, but never less than 3.

From our experience, the number of loops **SELF\_NLOOP** does not impact much the quality of the solution, and 2 to 3 iterations are usually sufficient.

**Warning:** the comparison with theoretical noise relies on a proper scaling of the weights of the UV data. This is fine for the IRAM array, but data exported from CASA is not always correct in this respect. **UV\_PREVIEW** can warn you about potential issues in this respect. **UV\_REWEIGHT** can also evaluate the scaling factor that should be applied to the weights to recover the apparent noise level. **UV\_PREVIEW** requires a sufficient number of spectral channels for this purpose. By default, **UV\_REWEIGHT** suffers from a similar restriction, and both commands may fail if the bandwidth is clobbered with spectral lines or has strong continuum. However, **UV\_REWEIGHT** as a **TIME** mode where the noise is estimated from consecutive visibilities, and thus is not affected by this limitation.

The appropriate scaling factor can be specified in **SELF CAL** by variable **SELF\_SNOISE**.

## 9.5 Advanced use

### Amplitude self calibration

The amplitude calibration (**SELF CAL AMPLI**) is a secondary step in the self-calibration process. In general, it should only be attempted if the phase calibration was already excellent, i.e., once you obtained the best solution by adjusting the **SELF\_TIMES** parameter for the **SELF CAL PHASE** command. If possible or needed, the amplitude self-calibration should use a *longer timescale* than the phase calibration (typically, **SELF\_TIMES** = 120 s). **SELF CAL** automatically adjusts the gains so that their mean is 1, in order to avoid changing the flux scale. In practice, it is useless if the expected noise limited dynamic range is less than about 300.

#### Cases where Amplitude self calibration may be essential

If **PHASE** self-calibration does not sufficiently improve the image despite ample signal-to-noise, Amplitude self calibration may do it. This situation often occurs when the observations span different dates, so that the relative flux calibration between the separate dates is inconsistent. In this case, a **AMPLI** self-calibration may be of great help. For compact sources, the flux consistency scale across dates can be also checked and cured using command **SCALE\_FLUX**.

Note however that the resulting improvement does not necessarily produce a higher fidelity image. It removes the inconsistencies, but the selected (average) flux scale has no guarantee to be good. Flux calibration should be independently checked if this situation occurs.

### Support restriction, flux threshold

Support restriction in the **CLEAN** process may be needed to build a simpler model for very complex, extended sources only. Command **MASK THRESHOLD** can be useful in this respect. Similarly, limiting the flux per pixel in the model (see **SELF\_MINFLUX**) may help, since noise peaks are then ignored. However, the later may fail if the source is too extended: low level brightness can be important for self-calibrating short baselines.

## 9.6 Transferring the solution to other *uv* data sets.

An important use of the Self-calibration is to compute a calibration solution using wide bandwidth data (*continuum* data, where signal-to-noise can often be maximized) and apply it to high spectra resolution (*line*) data.

The technique is quite simple. Solve for Self-calibration using the wide bandwidth data as usual, and save the results (gain tables) using the **WRITE CGAINS** command (eventually one for each of the **PHASE** or **AMPLI** steps of Self-calibration).

At any time, you can read back these gain tables using **READ CGAINS**, read an *uv* data set with **READ UV** and apply the gain solution using command **APPLY**. Since Self-calibration normally corrects for atmospheric errors, the derived ‘phase’ correction is in general here to compensate for a pathlength change, i.e. the corresponding phase correction should scale as Frequency. **APPLY DELAY** instructs **IMAGER** to take this effect into account.

## 9.7 Data re-weighting

The data weights are not changed during the self-calibration solution search.

However, when applying the gain changes, the **SELFAL APPLY** command implementation makes a conscious choice the consequence of amplitude changes on the data weights. The weights are scaled down when the amplitude is increased (as thermal noise is also increased in proportion), but are untouched if the amplitude is decreased. In essence, **IMAGER** considers that self-calibration always degrades the noise.

Note that as a result of the different behaviour for the weights during the search and in the use of the solution, the last iterated image in the self-calibration search is not the image obtained after applying the solution. Even the angular resolution may change (hopefully only slightly).

This of course only applies for **AMPLI** self calibration, since phase changes do not affect the noise.

## 9.8 Data flagging

Self-calibration is intended to improve upon a basically good solution.

When corrections are too large, it may be wise for the user to flag data that suffer from excessive corrections. This is possible *a posteriori* (i.e. after a **SELFAL APPLY** command) using command **SELFAL FLAG** as below

```
selfcal flag [Threshold]
```

**Threshold** is the correction above which data should be flagged (in degrees for Phase or Delay, no units for Ampli). Like for **SELFAL APPLY**, the current value of **SELF\_MODE** is used to determine the mode.

Apart from minor verifications and messages upon the self calibration solution validity, the command is equivalent to command **APPLY /FLAG**

```
apply 'self_mode' 0 /flag [Threshold]
```



## 10 UV plane analysis

**IMAGER** is not only a tool to produce images. It also allows direct analysis by model fitting to the UV data.

A number of commands are directly related to these possibilities:

- **READ UV**
- **READ MODEL**
- **SHOW UV\_FIT**
- **SHOW UV**
- **UV\_CIRCLE**
- **UV\_CONTINUUM**
- **UV\_DEPROJECT**
- **UV\_FIT**
- **UV\_RESIDUAL**
- **UV\_RADIAL**
- **UV\_SELECT**

The overall intent of these commands is described below. Please refer to the corresponding **HELP** for more details about the command syntax, options and control values.

- **UV\_FIT** is the primary fitting command. It allows to adjust simple, analytic models of source brightness to the current UV data. Up to 8 different source models can be combined in a single fit <sup>8</sup>.

The **UV\_FIT** results can be displayed using command **SHOW UV\_FIT**. The visibilities modeled by **UV\_FIT** (or the fit residuals) can be displayed using command **SHOW UV**, either alone, or superimposed to the current UV data.

**UV\_FIT** works on spectral line data. To optimally fit continuum data, it is best to convert the spectrally resolved information into a *bandwidth synthesis continuum uv* table.

- **UV\_CONTINUUM** converts a spectral line *uv* table into a *bandwidth synthesis continuum uv* table. **UV\_CONTINUUM** requires some knowledge of the field of view to evaluate how many channels should be averaged together. This is done using the same parameters (**MAP\_FIELD**, or the product of **MAP\_SIZE** by **MAP\_CELL**) and subroutines as for commands **UV\_STAT SETUP** and **UV\_MAP**.

The *bandwidth synthesis continuum uv* table is peculiar in the sense that it has several baselines for the same pair of antennas at the same observing time: one baseline per independent frequency point, in order to preserve optimally the angular resolution that goes as  $\lambda/B$ . In practice, it is only useful for **UV\_FIT**, but not suitable for self-calibration for example.

- **SHOW UV** will display the best fit visibilities (stored in the **UV\_MODEL** data set) if (and only if) the **UVSHOW%FIT** variable is set to **MODEL**, **POINT** or **CURVE**. When **UVSHOW%FIT** variable is set to **MODEL**, the **UV\_MODEL** data set is assumed to exist, and not re-computed. It is displayed as data points (not as a curve).

---

<sup>8</sup>this is probably too much, and would most likely lead to instability in the model fitting !..

- **SHOW UV\_FIT** is intended to display the fit results (the best fit parameter values and their errors) as a function of channels (or velocity, or frequency). This is often a nice way to show the detection of a signal when the signal to noise is limited, but of course is useless for single channel data !
- **READ MODEL** can import the visibilities from an outside model, so that these can be overlaid to the current UV data by **SHOW UV** with **UVSHOW%FIT** variable set to **MODEL**.
- Command **MODEL** computes the visibilities (the **UV\_MODEL** dataset) for the best fit parameters found by **UV\_FIT** or for the selected Clean components, depending whether **UV\_FIT** or **CLEAN** was used last.
- Similarly to command **MODEL**, **UV\_RESIDUAL** computes the residual visibilities (the **UV\_RESIDUAL** data set).
- Commands **UV\_CIRCLE** **UV\_DEPROJECT** **UV\_RADIAL** can be useful in conjunction to **UV\_FIT**, as they can provide a (deprojected, optionally azimuthally averaged) visibility data set which can be much more easily compared to simple, circularly symmetric models.  
Beware that the convention for *angle* are different in these commands (that use the PA of the axis) and **UV\_FIT** that use the PA of the major axis: they thus differ by 90 degrees.
- Finally, command **UV\_SELECT** allow to select which data set is displayed by **SHOW UV** among the UV data, the **UV\_MODEL** or the **UV\_RESIDUAL**.

Try @ [gag\\_demo:demo-uvfit](#) for some examples.

## 11 Continuum emission

**IMAGER** naturally handles many spectral channels. However, the astronomer may be interested in broad-band continuum emission. Extracting the properties of such a continuum emission may be a difficult issue in some cases. **IMAGER** offers a number of tools to do so, including the notion of a **CONTINUUM** image.

To first order (over a limited frequency coverage), continuum emission can be represented by a flux (at some reference frequency) and a spectral index. Both flux and spectral index may vary spatially. Such a representation is often valid over a factor 2 or 3 in frequency. In general, the spatial distribution of these properties of the continuum emission may be widely different from those of the spectral lines. Furthermore, spectral lines can be easily optically thick at some velocities, and may hide the continuum emitted from behind, and thin at others. The continuum itself may sometimes have sufficient opacity to obscure line emission.

Thus a proper extraction of the continuum properties can formally only be done in the image plane, after imaging the combined continuum and spectral line emission, and cannot rely on a separation in the  $uv$  plane at the level of the visibilities.

In general, this cannot be done by simply imaging channel per channel. The reason for that is that continuum emission is in general fainter than the spectral line one, and often faint enough to have only limited signal to noise in a single channel. Deconvolution of such emission is noise limited. Yet, when averaging over many channels (PolyFix on NOEMA offers 2048 channels per wide band window, ALMA has up to 4096 per spectral window), the S/N changes by a large amount, and the undeconvolved sidelobes from the continuum emission appear.

### 11.1 Continuum imaging

To avoid this, it is better to deconvolve the continuum emission by averaging as many channels as possible. Line emission should be filtered as much as possible at this level, since otherwise it contaminates the information which is sought. A further issue is that the effective resolution of the array goes as  $\lambda/B$ . With a wide enough frequency coverage, this is a significant change over the bandwidth that must be accounted for. It actually helps to obtain a better  $uv$  coverage, a process called *bandwidth synthesis*.

In **IMAGER**, the whole process can be done in four commands

```
uv_preview
uv_filter
uv_map /cont
clean (and optionally uv_restore)
```

- Command **UV\_FILTER**, used after **UV\_PREVIEW**, will remove all regions of the spectrum that are contaminated (above the noise level) by spectral lines.
- Command **UV\_MAP /CONT** will then image in bandwidth synthesis the remaining continuum emission. After that, **CLEAN** and **UV\_RESTORE** can deconvolve and properly restore the image.

In command **UV\_MAP /CONT**, the user can specify the spectral index of the emission to optimize the signal to noise by giving the best weight to each spectral channel.

This part is only a first step in a proper analysis. The next one is to image the remaining signal in spectral lines, and ultimately add back the deconvolved continuum image. To help the user in this, the image obtained as above is automatically saved as the **CONTINUUM** SIC image variable.

## 11.2 Split Continuum and Spectral line imaging

To image the spectral line, we simply remove in the *uv* plane the continuum defined before and image the resulting spectral line data:

```
uv_baseline
uv_map
clean (and optionally uv_restore)
```

The last step is to add back to this image the deconvolved continuum one:

```
define image my_clean * real /like clean /global
map_combine my_clean ADD clean continuum
```

where the last command is equivalent to the following loop:

```
let my_clean% clean% ! Set its header
for i 1 to clean%dim[3]
let my_clean[i] clean[i]+continuum
next
```

Because the Fourier Transform is a linear operation, we end up with a combined data set that properly includes all the emission, line and continuum, deconvolved in a (well almost...) <sup>9</sup> optimal way.

Further analysis of the spatial variations of the continuum emission (including variations of its spectral index) can be done on this combined image that contains all the information, see Sec.11.4

Note that we used in this example commands `uv_filter` and `uv_baseline` with their default behaviour provided by `uv_preview`: the user could specify more adapted values using the command options and/or control variables if needed.

## 11.3 Combined Continuum and Spectral line imaging

An alternative to the method described in Sec.11.2 is to use the Continuum image, or more precisely the Continuum Clean Components, as a starting point for the deconvolution of the continuum+line data. The first step is to save the Continuum Clean Components:

```
uv_preview
uv_filter
uv_map /cont
clean
write cct Continuum.cct
```

Re-imaging the data set with the continuum included can be done by `uv_filter /reset`

```
uv_map
read cct Continuum.cct
clean /restart
```

`uv_restore` (as an optional step).

`UV_FILTER /RESET` reset the weights of the line emission channels to their proper values. Reading again the Clean Component list is needed because `UV_MAP` destroys this list. The Clean Component list of the continuum data is then used as a starting value for every spectral channel by the `CLEAN /RESTART`.

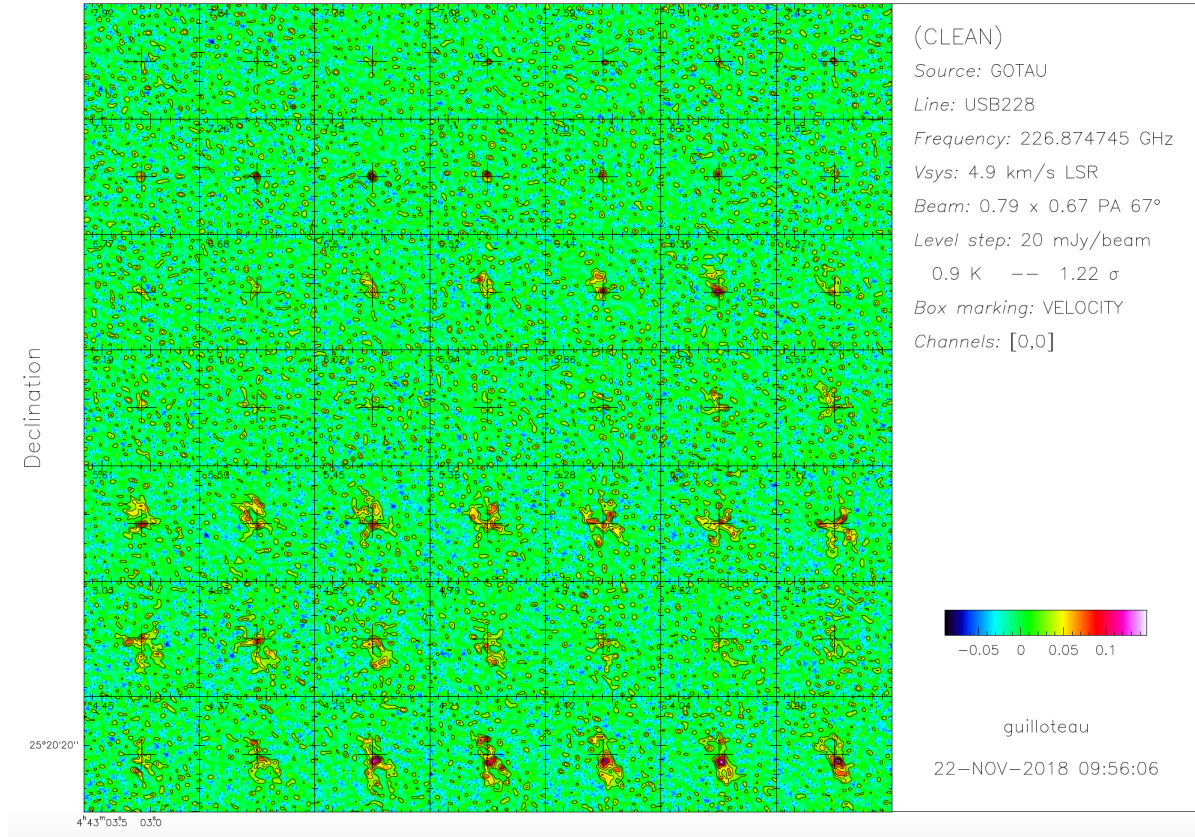
---

<sup>9</sup>The combination is only optimal if the spectral index has no spatial variations. A better handling of spatially variable spectral index is under study.

#### 11.4 The CONTINUUM image

The `CONTINUUM` image can also be produced from a (deconvolved) spectral line data cube by the `MAP_CONTINUUM` command. Compared to the method presented in Sec.11.1, this has the advantage of being able to handle spatially variable spectral index, and also spatially variable spectral line contamination. It has the drawback of limited S/N for the deconvolution, as already mentioned, unless the spectral line data cube also contains the continuum emission using one of the two methods presented in Sec.11.2-11.3.

Also, the `CONTINUUM` image can be read from a GILDAS data file using command `READ CONTINUUM`. And of course, it can be written to GILDAS data file by command `WRITE CONTINUUM`.

Figure 2: The **SHOW CLEAN** output.

## 12 Visual Checks and Image Displays

The ultimate (and often sole) way to evaluate the data quality and suitability for scientific analysis is to visualize it. **IMAGER** offer simple, yet powerfull, tools to do so.

Most visualization (or related) commands are grouped in language **DISPLAY\** (which may be used alone to provided a simple stand-alone data cube visualisation tool.).

### 12.1 The **VIEWER** program

The **VIEWER** program is a subset of **IMAGER** that only contains the **DISPLAY\** language. It can be used to provide visualisation of any GILDAS data cube. Besides visualisation commands that are described in the sub-sections, **VIEWER** includes the **CATALOG** (and its related **FIND** command) that controls the behaviour of some displays, as well as generic support commands like **STATISTIC**

#### 12.1.1 The **SHOW** command

In general, command **SHOW** allows a per-plane display of any SIC 3-D image variable, with contours overlaid on bitmap for each plane: e.g.

**SHOW DIRTY 30 -30** will display contour and bitmaps of each channel of the **DIRTY** image, starting for channel 30 and ending 30 channels before the last one. See Fig.2 for an example. Command **SHOW /SIDE** (and also command **SHOW** when the **SHOW\_SIDE** variable is set to **YES**) will call the cursor, so that the pixel values at the cursor position are displayed in the **<V****SIDE** panel.

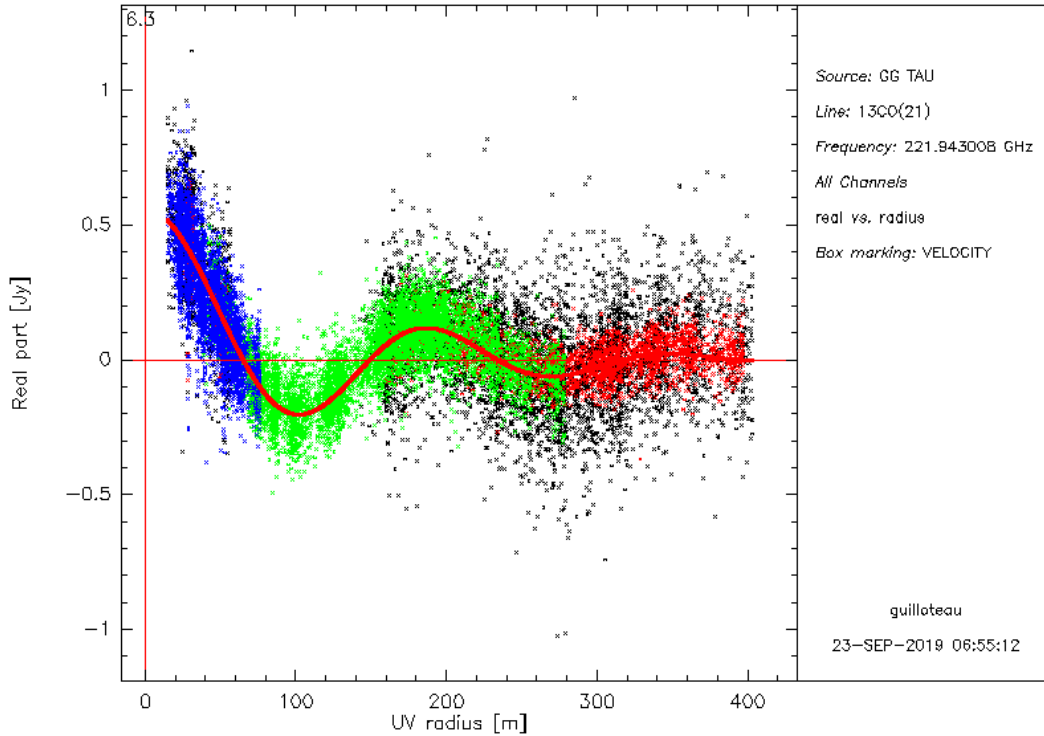


Figure 3: The `SHOW UV` output with results from `UV_FIT` command overlaid.

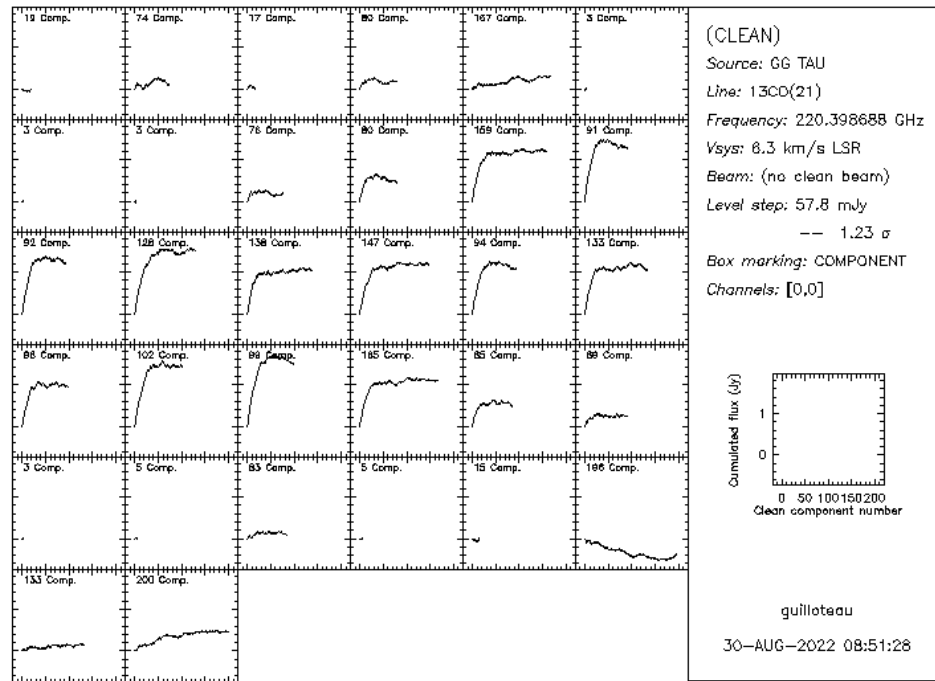
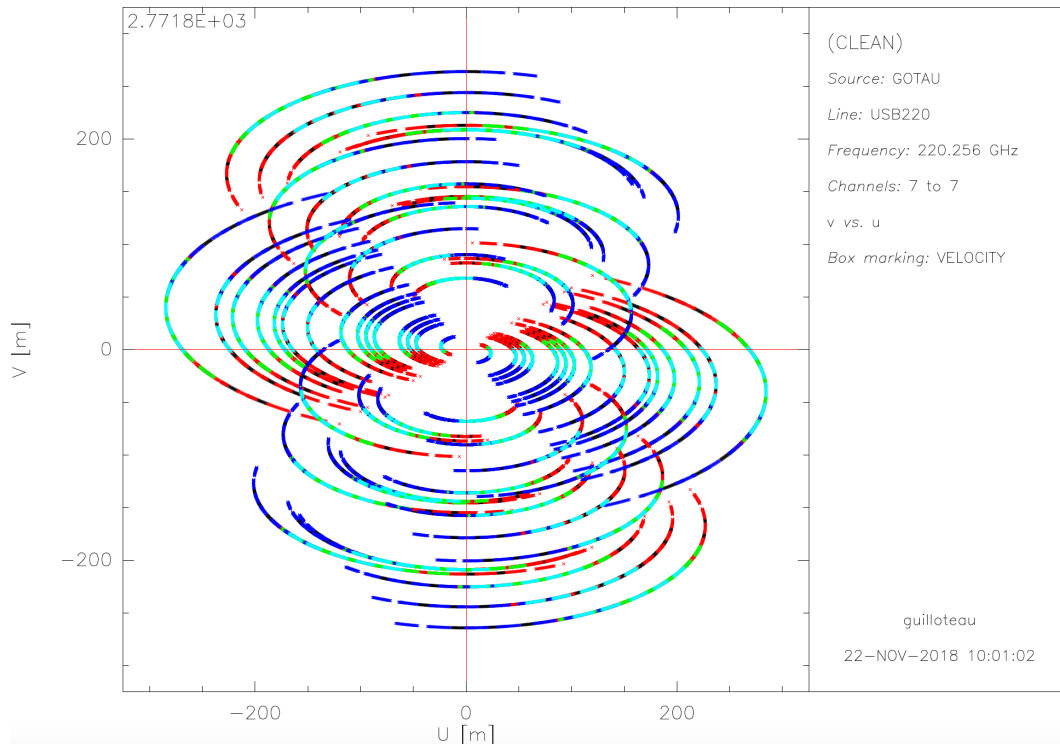
A direct use on Gildas 3-D image or UV data files is also possible: `SHOW Filename.ext` will directly display the file if possible. It also works for simple FITS files in which the data array is in the HDU.

For *uv* data, `SHOW UV` can plot visibility values such as amplitude as a function of time, baseline length, etc..., again on a per channel basis. Fit results can be overlaid, as shown Fig.3 `SHOW` can also display more specific issues:

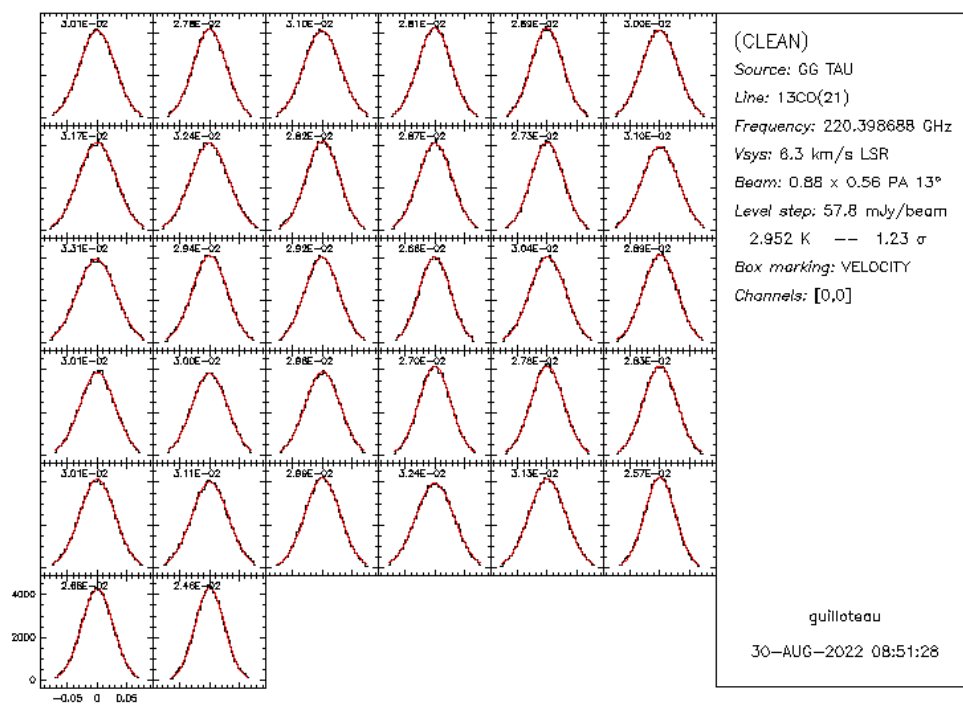
- `SHOW CCT` will display the cumulative flux as a function of number of clean components (Fig.4).
- `SHOW COVERAGE` will display the *uv* coverage (it assumes there is only one, and not one per channel, because the display time is long, see Fig.5)
- `SHOW SELFCAL` behaves as `SELFCAL SHOW`
- `SHOW FIELDS` displays the fields of a Mosaic.
- `SHOW NOISE` displays the histogram of the intensity distribution for each channel, estimating the noise by fitting a Gaussian in these histograms (see Fig.6).
- `SHOW UV_FIT` displays the `UV_FIT` results for spectral line data.

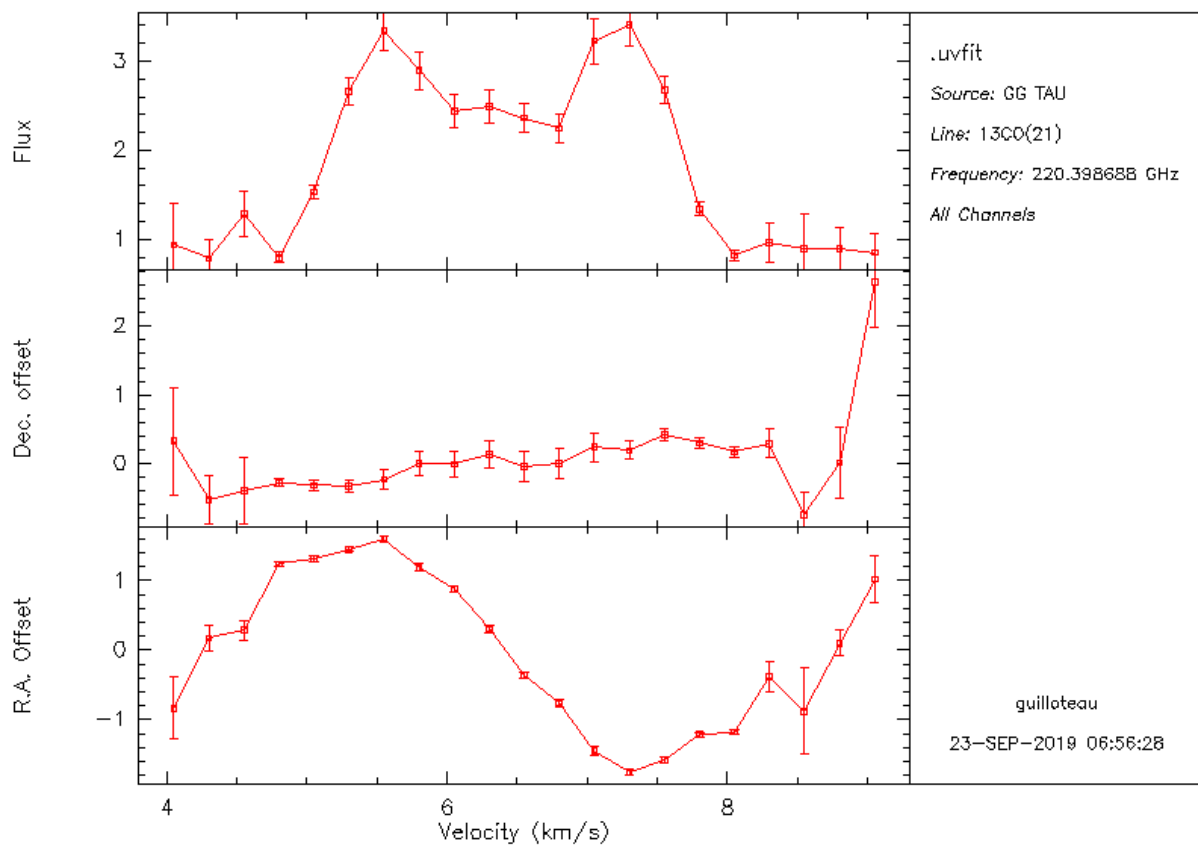
`SHOW` recognizes many other keywords. See `HELP SHOW` for further details.



Figure 4: The **SHOW CCT** output.Figure 5: The **SHOW COVERAGE** output. Colors indicate different dates.



Figure 6: The **SHOW NOISE** output.

Figure 7: The `SHOW UV_FIT` output.

### 12.1.2 the VIEW command

The **VIEW** command is a powerful alternative to **SHOW**, the later being inefficient when the number of spectral line channels is large.

**VIEW** provides a 4 panel display for 3-D data cubes, with the current channel bitmap, the integrated area bitmap, the current spectrum and the integrated intensity spectrum. The spectra can be displayed with 2 simultaneous frequency windows, a broad and a zoomed one, allowing browsing through a large number of channels. Spectral line identification (from the line catalog specified using command **CATALOG**) can be added by typing **L** when the cursor is on one of the 2 broad-band spectra.

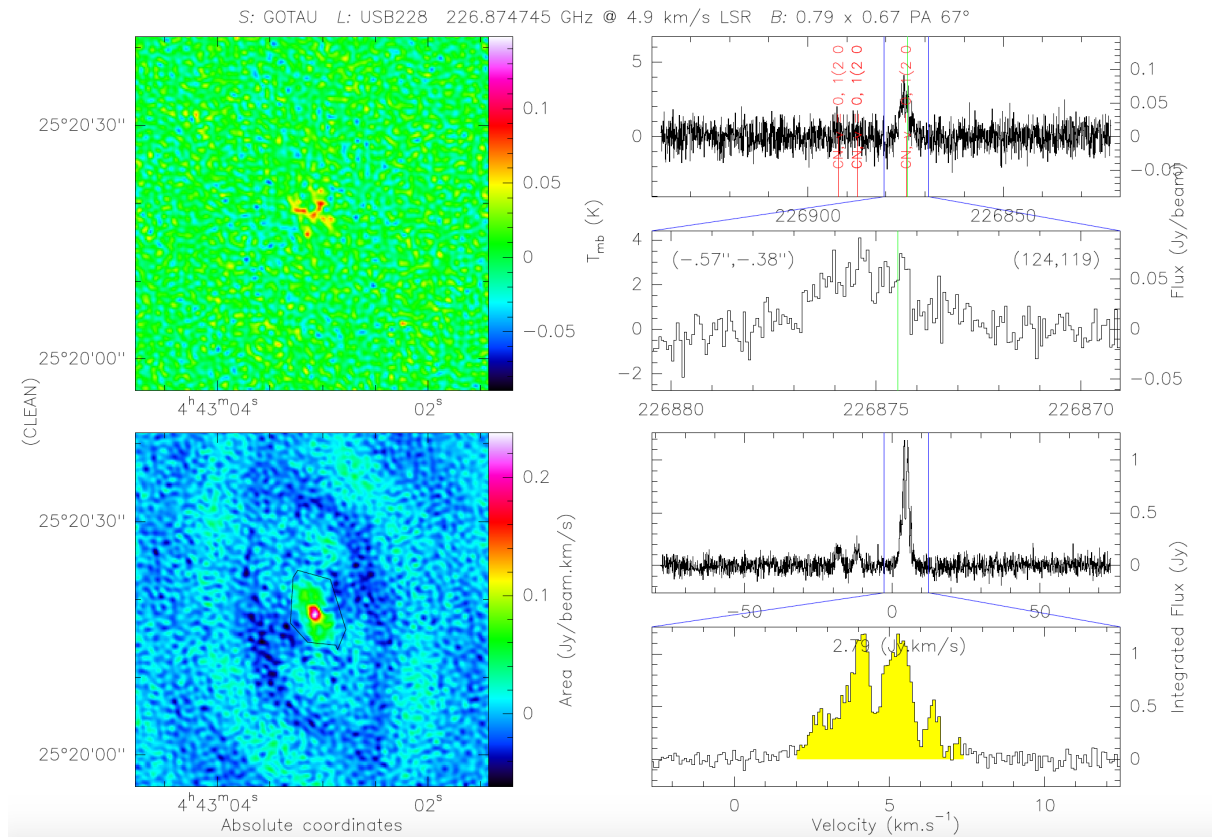


Figure 8: The **VIEW** output.

**VIEW CCT** will display the cumulative flux of Clean components for all channels in just one panel, instead of a per-channel panel for **SHOW CCT**.

Similarly, **VIEW NOISE** will plot all pixel intensity distributions from every plane in a single panel, contrarary to **SHOW NOISE**.

**VIEW /OVERLAY** allows to overlay (in contours) the plane of a second data cube. The main use is to overlay the continuum, or a plane of the current data cube to help revealing velocity structures.

**VIEW** will fallback to **SHOW** whenever it has no specific support for a given action.

Like **SHOW**, **VIEW /NOPAUSE** will not loop interactively to explore the data cube, but just display the view with its current parameters (channel, velocity range, support). The same behaviour can be obtained by setting **DO\_LOOP** to **NO**.

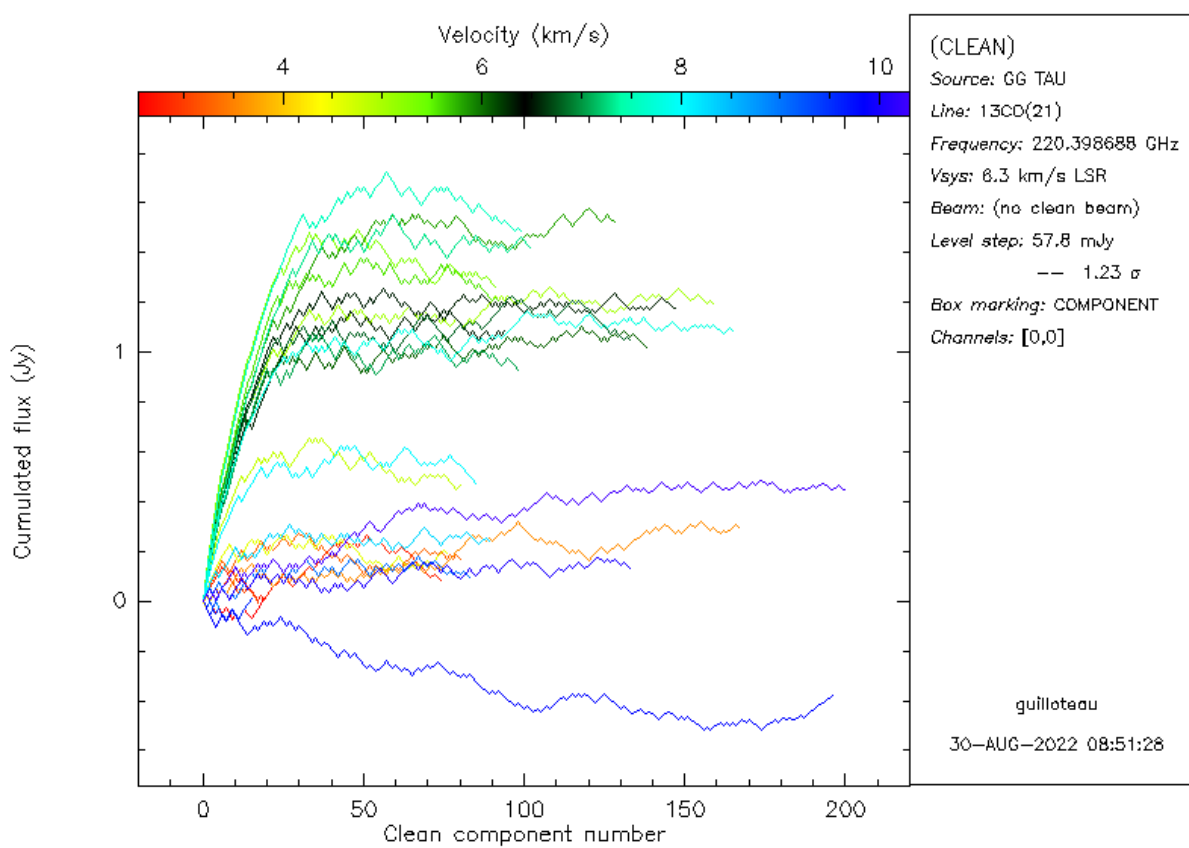


Figure 9: The VIEW CCT output.

### 12.1.3 the INSPECT\_3D command

Another alternative to **SHOW** or **VIEW** is the **INSPECT\_3D** command, which presents cuts along the 3 main directions of the data cube (xy, xv, vy). Like **SHOW /SIDE** and **VIEW**, **INSPECT\_3D** has a <V>SIDE display panel where data values at current position are displayed.

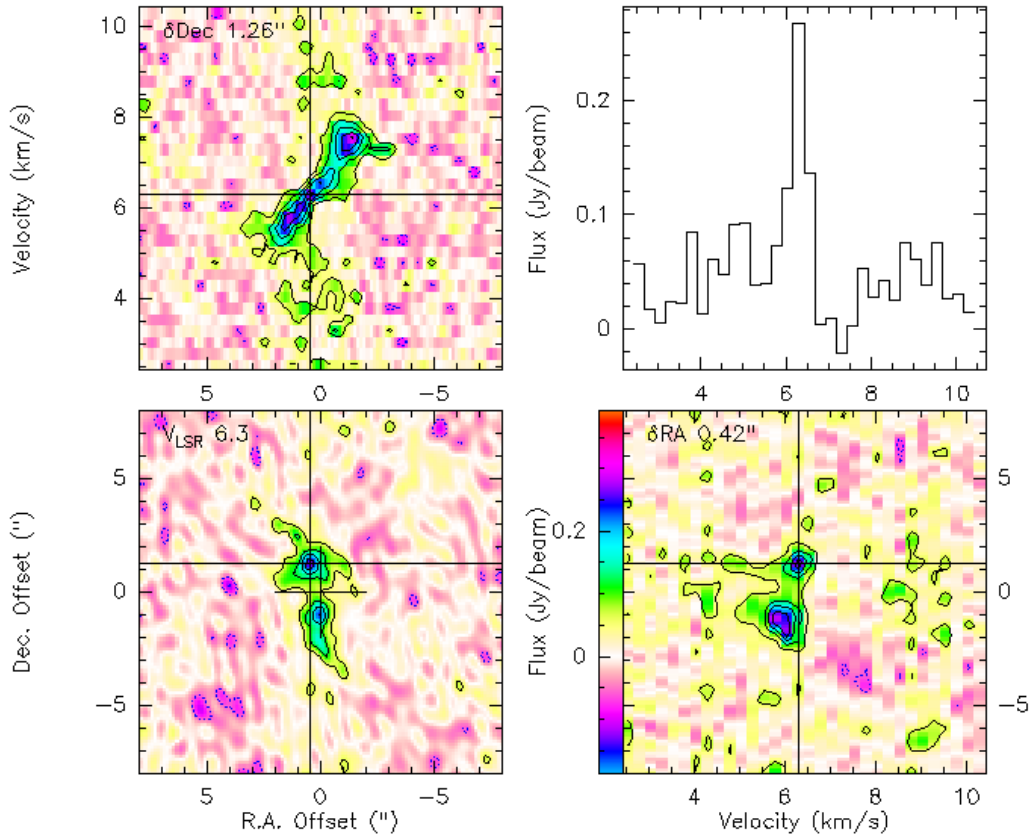


Figure 10: An **INSPECT\_3D** output. Cursor controls the coordinates of the 3 orthogonal cuts and spectrum.

#### 12.1.4 the EXPLORE command

The latest alternative to **SHOW**, **VIEW** or **INSPECT\_3D** is the **EXPLORE** command, which presents spectra extracted from a datacube around an image of one velocity channel or of the velocity integrated area.

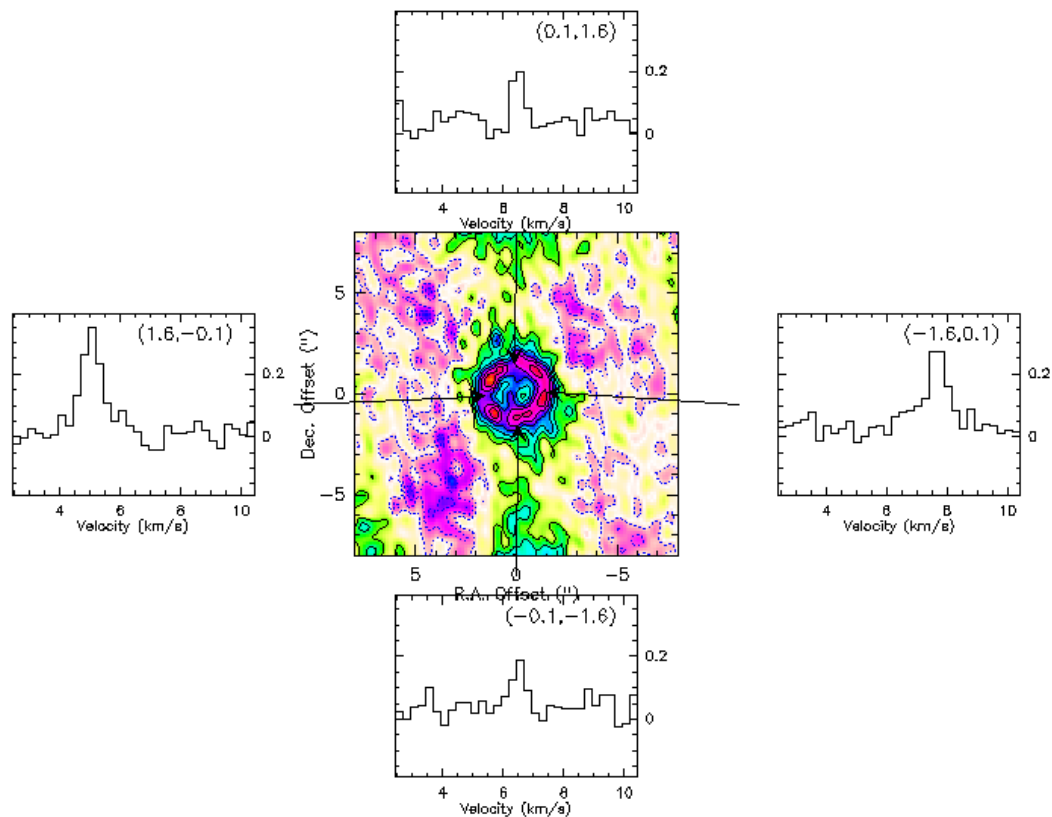


Figure 11: A sample **EXPLORE** output. Up to 8 spectra can be displayed around the central image.

## 12.2 Specific IMAGER visualisation tools

In addition to the generic tools offered in the `DISPLAY\` language, `IMAGER` contains commands that are more specific to the UV data handling or imaging process, or to advanced analysis commands. The former category includes `UV_PREVIEW`, as well as `SELF CAL SHOW`, while an example of advanced specific display command is `KEPLER SHOW`

Like `SELF CAL`, some other commands (e.g. `KEPLER SHOW`) have a `SHOW` mode. In general, `SHOW` will then recognize the reverse syntax, `SHOW KEPLER` in the above example.

Use `HELP SHOW` for more details, as the Help is in general more up-to-date than the compiled documentation which is more intended to document general features.

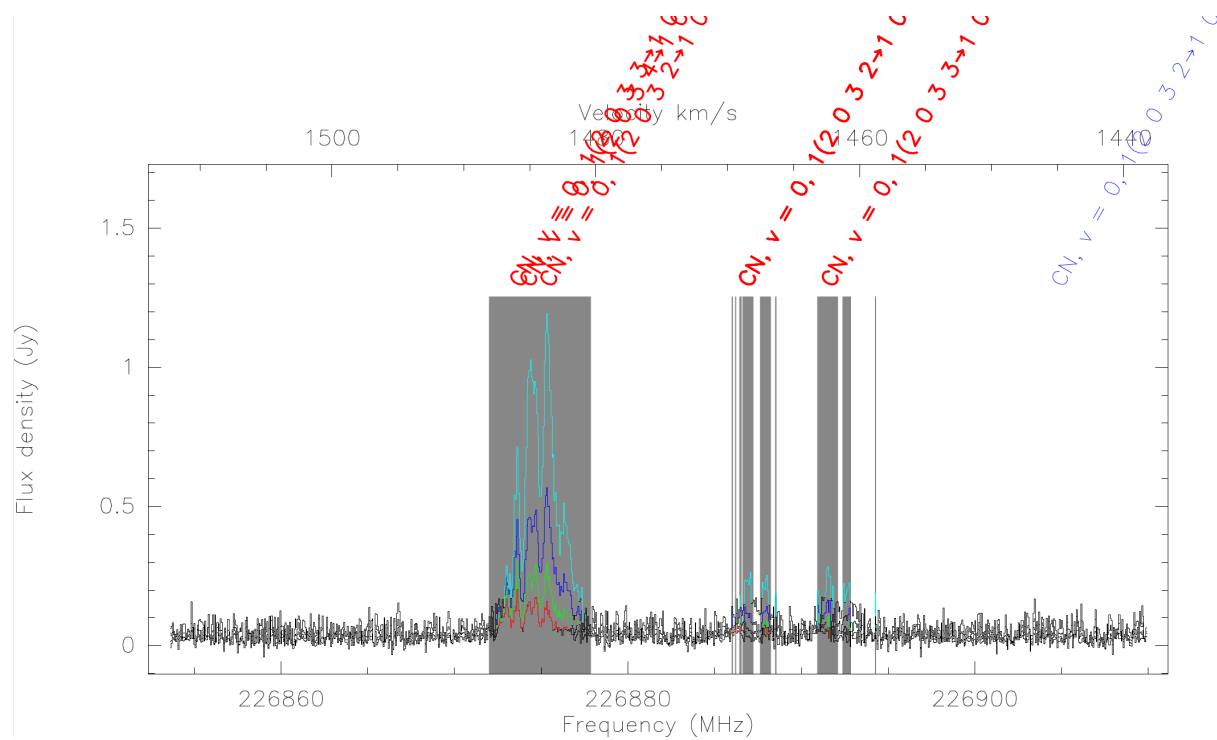
### 12.2.1 The UV\_PREVIEW command

With large datasets, imaging can be long. `IMAGER` offers a simple, fast pre-imaging viewer through command `UV_PREVIEW`.

This command will display the spectra obtained towards the phase center at several spatial scales (the default is for 4 tapers). It will also attempt to detect spectral features, by analyzing for each spectrum the noise statistics and the outliers. It performs automatic line identifications, using database(s) in the `LINEDB\` or `ASTRO` data format selected by command `CATALOG`. Potential spectral lines in the band are displayed in blue, and detected ones in red. `UV_PREVIEW` also warns the user about improper scaling of the data weights. The line emission region is indicated in grey.

The result of this automatic signal detection and line identification is saved in a SIC structure named `PREVIEW%`, that is automatically used by commands `UV_BASELINE /CHANNELS` and `UV_FILTER /CHANNELS` to respectively remove the continuum and filter the line emission to produce a continuum data set. The detected line frequencies are stored in `PREVIEW%FOUND%FREQ` and their names in `PREVIEW%FOUND%LINES`. This can be used to reference the velocity scale of the data to one of the detected lines, by using command `SPECIFY FREQUENCY 'PREVIEW%FOUND%FREQ[1]'` for example before further processing.

An example is shown in Fig12

Figure 12: The **UV\_PREVIEW** output



### 12.2.2 the SELF CAL SHOW command

Verifying the convergence of a self-calibration is important. Figure 13 shows an example, while Fig.14 shows the total phase correction between the original data and the last iteration.

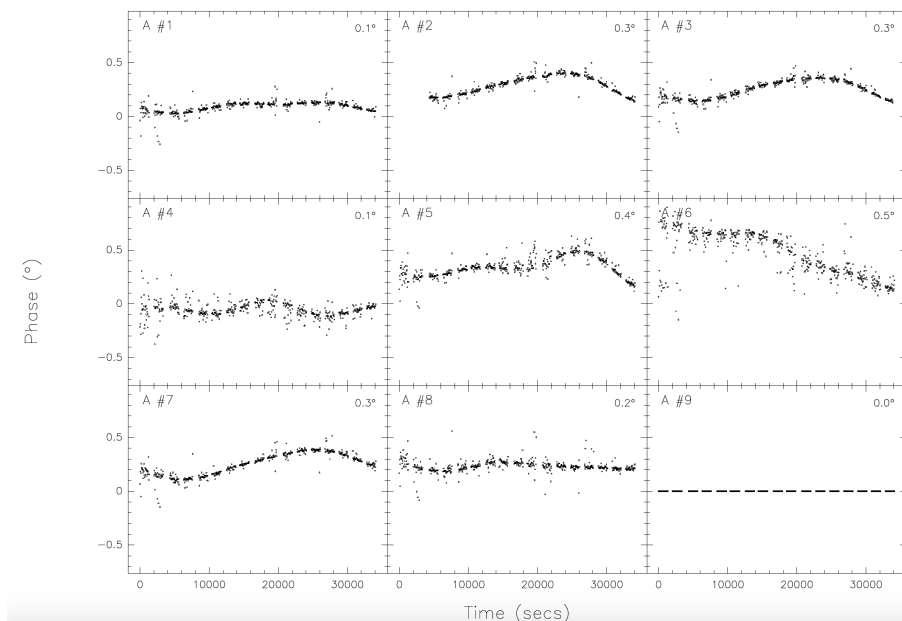


Figure 13: The **SELF CAL SHOW** output after a phase calibration, showing the convergence of the corrections between the last 2 iterations.

The displayed range can be controlled by variables **SELF\_PRANGE[2]** for the Phase, **SELF\_ARANGE[2]** for the Amplitude, and **SELF\_TRANGE[2]** for the Time. Error bars are displayed if **ERROR\_BARS** is YES, as shown in Fig.15 for amplitude.

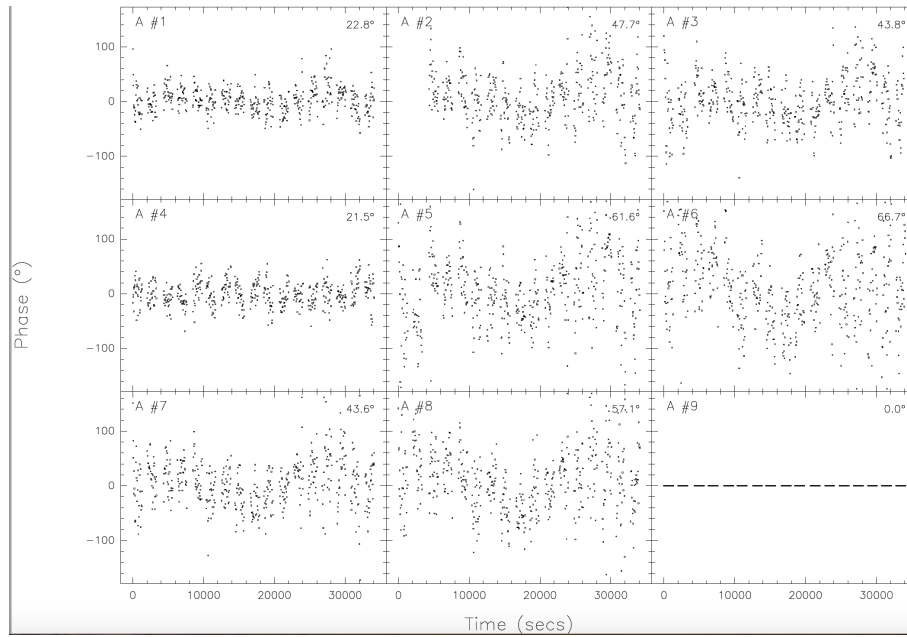


Figure 14: The **SELF CAL SHOW** 4 output after a phase calibration, showing the difference between iteration 4 and the original data.

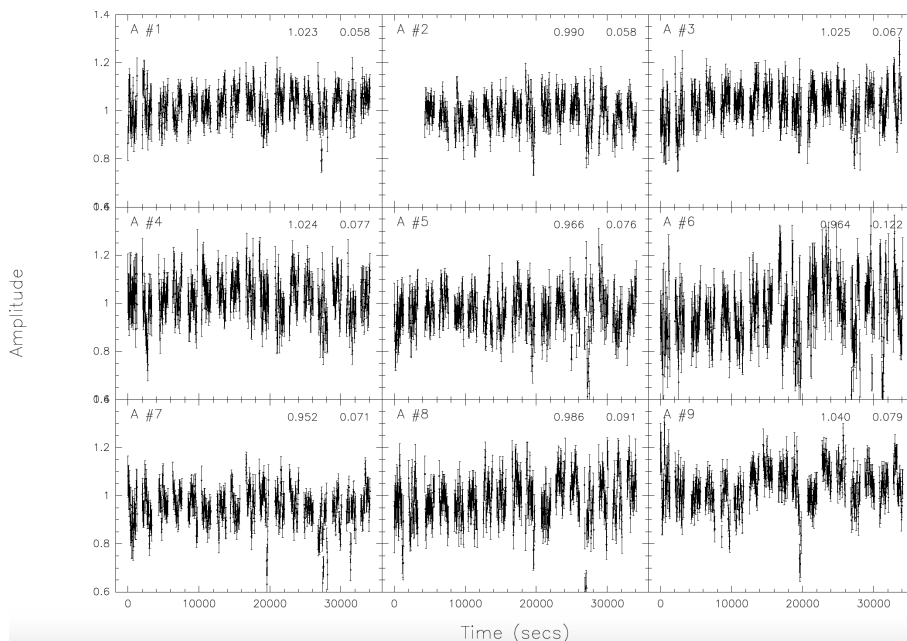


Figure 15: The **SELF CAL SHOW** 4 output after an amplitude self calibration, showing the difference between iteration 4 and the original data, with the error bars.

## 13 The Imager PIPELINE tools

With ALMA or NOEMA, you may end up with an observational data set that contains several sources, each of them observed with a number of spectral windows of different spectral resolutions, covering many spectral lines.

The bookkeeping of such data sets can be intricate. To help the users to focus on the science, we have developed a pipeline (namely a suite of scripts named `all-*.ima`) that automates the whole imaging process in this case. This pipeline can be run through the `PIPELINE` command, or through a control panel launched by the `PIPELINE /WIDGET` command.

The pipeline control parameters are available in the `ALL%` global structure, and can be checked using the `PIPELINE ?` command.

The pipeline is intended to handle all spectral sub-bands for a single receiver tuning of the interferometer, with the data (possibly with several observing dates) for each sub-band and each source stored in a separate file (in UVFITS or GILDAS UV format).

The principle is to gather all UV tables in a sub-directory (named `./RAW/` by default), and to store the results of the various processing steps (Self Calibration, Spectral line extraction, Imaging) in different sub-directories (respectively named `./SELF/`, `./TABLES/`, `./MAPS/` by default).

The behaviour of the Imaging step depends on the pipeline mode, `ALL%MODE`, that can be controlled by the `PIPELINE /MODE` option. It also depends on whether a `CATALOG` is used or not, and on the `ALL%RANGE[1:3]` variable that controls the velocity span and resolution.

- **CONTINUUM Mode:**  
In this mode no data cube is produced. Only continuum images are created, with no attempt to remove any contaminating line emission.
- **SURVEY Mode**  
In this mode, there is also no spectral line emission filtering. Full data cubes are produced, at the spectral resolution specified by `ALL%RANGE[3]`. No continuum image is produced: continuum can be later extracted through the `MAP_CONTINUUM` command.
- **SPLIT Mode**
  - Without a spectral line catalog, the Imaging step will make no attempt to identify spectral lines, and thus no attempt to image each line separately. Instead, each “high spectral resolution” UV table will be imaged completely. An automatic estimate of the continuum level is made, and is imaged separately from the continuum-subtracted data. At the end of the process, the deconvolved “continuum” image is added back to the spectral image. “Low spectral resolution” data only produce a continuum image. This mode is appropriate for e.g. low spectral resolution data, very wide lines, and/or nearly confusion limited data with many spectral lines.
  - With a line catalog, a user-specified velocity range is imaged separately around each line in the catalog that falls into the observed frequency coverage. Continuum and Line are separated, but no attempt is made to add back the continuum data at end.
- **ALL Mode**  
This mode is similar to the SPLIT mode, except that no attempt is made to produce continuum-free line data cubes. The line data cubes also include the continuum data. This mode is appropriate when the continuum emission has spatial variations of its spectral index.

Naming conventions apply to identify which data set covers which spectral line.

### 13.1 Preparing the data

For NOEMA, the UV data can be created from the `.IPB`, `.hpb` raw data files using the `CLIC` script `@ all-tables`. The resulting UV tables (`.uvt` files) should be placed in your working directory.

For ALMA, UVFITS files should be created from the original Measurement Set (`.ms` directory) using the `casagildas()` Python tool in CASA, and placed in your working directory.

Once your working directory is loaded with the `.uvt` or `.uvfits` files, you can start using the `all-widget` script, usually through the `PIPELINE /WIDGET` command.

It is recommended to separate data from different sources into different directory structures, to simplify further processing.

### 13.2 The PIPELINE Widget

This section describes the widget that can be used to control the image processing in a systematic way for an ensemble of UV tables. The (selected) UV tables must come from observations of the same source **and** correspond to a single frequency setup, so that all spectral windows share the same *uv* coverage and observing dates and times.

#### 13.2.1 Getting started: PIPELINE /WIDGET

`PIPELINE /WIDGET` creates a Widget that is used to customize the process and launch the various steps. It also creates (through a call to `@ all-create`) the `ALL%` structure and its components.

#### 13.2.2 ORGANIZE step

The `ORGANIZE` button will move the initial files (`.uvfits` and `.uvt` files) into an appropriate sub-directory structure. By default, `.uvfits` files will be in `./UVFITS/` (name controlled by `all%uvfits`) sub-directory, while `.uvt` files will be in `./RAW/` sub-directory (name controlled by `all%raw`).

If absent, the `.uvt` files will be created from the `.uvfits` ones, using default parameters (i.e. assuming unpolarized emission).

#### 13.2.3 FIND step

The `FIND` button will explore the directory containing the initial UV tables (`./RAW/` by default) to identify *Wide Band* UV tables, i.e. those that cover enough bandwidth to provide enough sensitivity for self-calibration on continuum flux.

This information will be used later to derive the self-calibration solutions from some UV tables, and apply it to others, typically narrow band spectral line data.

#### 13.2.4 SELECT step

The `SELECT` button will restrict the subsequent work on the files matching the "File Filter" field value.

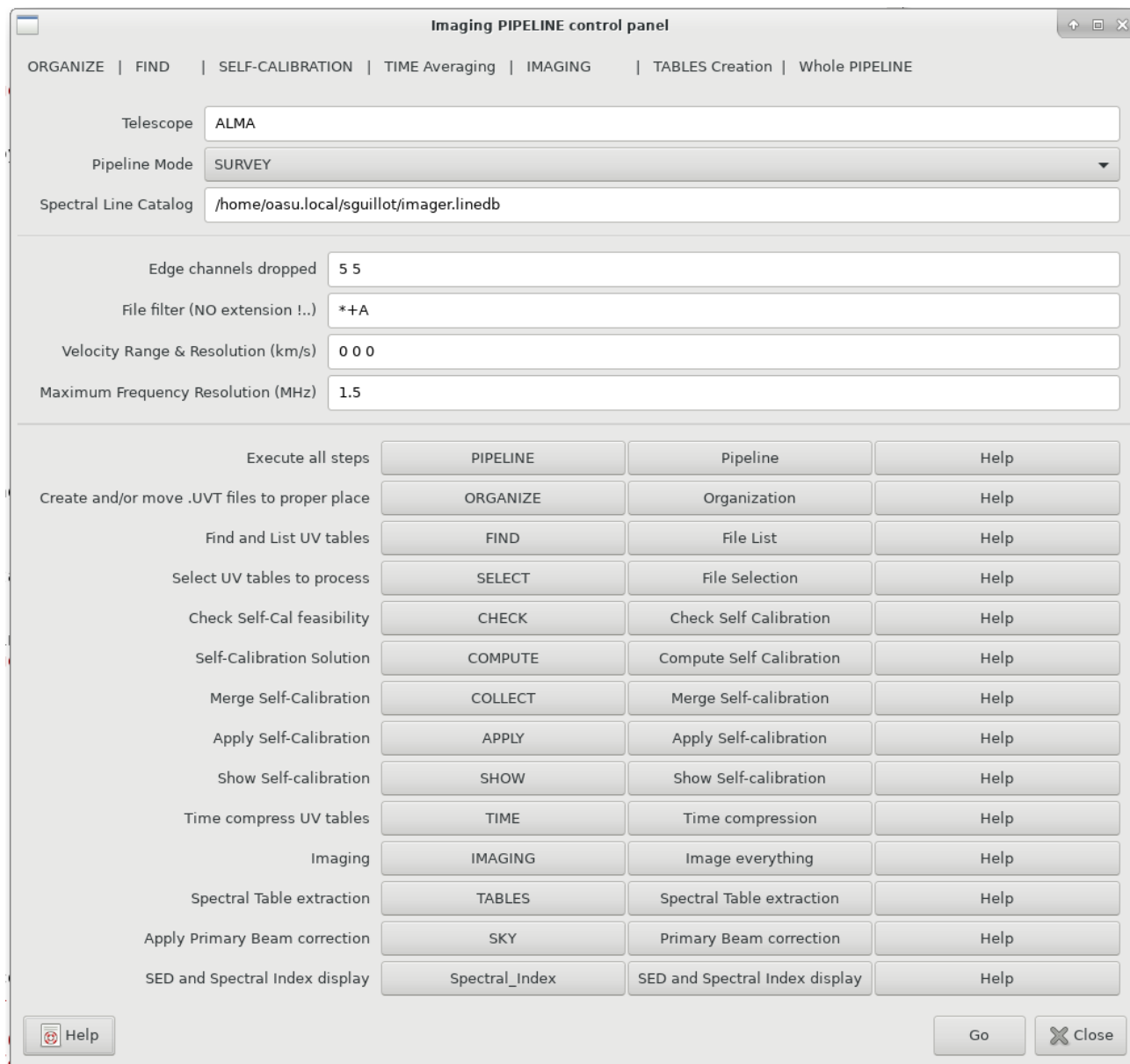


Figure 16: The Pipeline control widget. The two first lines of the widget cannot be modified directly. The **Telescope** information is derived by button **ORGANIZE** from the data set. The **Spectral Line Catalog** is defined through command **CATALOG**.

### 13.2.5 CHECK step

The **CHECK** button will use the list of *Wide Band* UV tables to check whether Self calibration may be needed and possible. The method is currently approximate and will be improved in future releases.

### 13.2.6 SELF step

The **SELF** button will use the list of *Wide Band* UV tables to compute a (phase and amplitude) Self calibration solution, and apply it to all UV tables. It will identify which UV tables correspond

to a given Wide Band one, so that the proper self calibration solution is applied.

The self calibrated UV tables are placed in another sub-directory (`./SELF/` by default, controlled by `all%self`).

A prefix (controlled by `all%prefix_self`) can be added to the file names to remind the user that they have been self-calibrated.

### **Caveats: CURRENT LIMITATIONS**

- No provision is made to use spectral line flux when the continuum flux is too low.
- Thus, if the Self-calibration solution is not good, you should not apply it. The `COLLECT` step may help at this stage.

#### **13.2.7 SHOW step**

This step will display the phase and amplitude correction that have been computed in the Self Calibration step. Optionally, these plots can be saved on Hardcopies (`.pdf` files for Pdf, `.eps` for EPS).

#### **13.2.8 COLLECT step**

Most NOEMA data include several wide bands (4 with PolyFix in its standard mode), and an independent Self-calibration solution is computed for each of them. The `COLLECT` button will merge all these solutions into a single one, assuming the phase errors are due to pathlength changes.

This improves the S/N of the self-calibration solution, and can be beneficial when the S/N is the limiting factor. On the other hand, if the data has very high S/N, this step may result in lower dynamic range than the application of the separate self-calibration solutions.

#### **13.2.9 APPLY step**

The `APPLY` button will apply the Self-calibration solution found in the previous steps (`SELF` and optionally `COLLECT`) to all UV tables. The selection of the solution to be applied is based on matching frequencies between the UV table and the solutions.

If the `COLLECT` step has been performed, one may still use the individual solutions by setting variable `ALL%COMBINE` to `NO`.

#### **13.2.10 TIME step**

The `TIME` button will time average the self calibrated UV tables to save space and speed up further processing.

The integration time can be specified, or left to 0. In this case, the data will be time-averaged to an appropriate sampling time given the longest baselines and field of view.

#### **13.2.11 IMAGING step**

The `IMAGING` button will scan all spectral windows to identify whether they can be used to produce a Continuum or spectral line image.

Low resolution spectral windows, identified as those whose resolution is coarser than `ALL%MINFRES` will be used to produce continuum images, by filtering any detected spectral signature in the data before.

High resolution spectral windows, identified as those whose resolution is better than `ALL%MINFRES`, data cubes will be produced.

In `SPLIT` Mode, if a Line Catalog is present, these high spectral resolution windows will be scanned for line identifications. For each spectral line in the current catalog(s) (defined by command `CATALOG`) that fall in a spectral window, a continuum-free UV table will be created, covering the velocity range specified by the user (by variable `ALL%RANGE`) around the line frequency. The naming convention is the following:

`original-molecule-I-X`

where

- `original` is the name of the initial high resolution spectral window
- `molecule` is the name of the spectral line in the catalog
- `I` is a sequence number, incremented each time a new line is found from the same original UV table.
- `X` is a character code, equal to `D` if the line is suspected to be detected, and to `U` if not. When several lines are too close together, the `D` status may be incorrectly affected, but this is just a naming convention, not a strong result.

In addition an

`original-C`

file that contains (presumably) line-free emission only is created for each original UV table.

The imaging results are stored in a specific sub-directory (`./MAPS/` by default, controlled by `all%maps`). Only the Clean Component Table (`.cct`) and Clean image (`.lmv-clean`) files are written.

When no Line catalog is present, only 3 images are produced for each UV tables: starting from the `original` name

`original-C`      `original-U`      and      `original-A`

The `...-C` contains (an estimate of) line-free emission, averaged over the bandwidth of the UV data. The `...-U` is the continuum subtracted image, while in `...-A` the pseudo-continuum image obtained in `...-C` has been added back. The `...-A` thus contains all the signal, and can be used to provide a better estimate of the continuum level using e.g. the `MAP-CONTINUUM` command.

Spectral resampling can be performed by appropriate setting of `ALL%RANGE`. If non zero, `ALL%RANGE[3]` indicates the desired spectral resolution. Furthermore, in the `CATALOG` case, `ALL%RANGE[1:2]`, if non zero, specify the Min and Max velocities imaged around each spectral line.

In `ALL` mode, the behaviour is similar, but only the `-C` and `-A` products are created.

In `CONTINUUM` mode, line emission is assumed to be negligible, and only the `-C` continuum images are produced.

### 13.2.12 TABLES step

The `TABLES` button performs the same scanning and identification process as the `IMAGING` button, but stores the resulting UV Tables (instead of the `.cct` and `.lmv-clean` files for the `IMAGING` button) in a sub-directory, named `./TABLES/` by default, controlled by `all%tables`.

This step is optional, and only needed if the user intends to perform some UV data analysis (like UV plane fitting, line stacking, continuum spectral index determination, direct modeling, etc...).

Extraction of the velocity range specified by `ALL%RANGE[1:2]` is performed if a `CATALOG` is provided by the user. Spectral resampling according to `ALL%RANGE[3]` is performed if and only if `ALL%RESAMPLE` is set to YES. Without no `CATALOG`, the full spectral coverage is preserved.

Except in CONTINUUM mode, line-free continuum UV tables are also produced.

### 13.2.13 SKY step

The SKY button will apply primary beam correction to the deconvolved images. This button has no effect for Mosaics, as sky brightness distributions are directly produced in this case.

## 13.3 The non interactive PIPELINE

The whole series of actions available through the Pipeline Widget can be performed in series through the `PIPELINE` command.

Command `PIPELINE *` will perform all the actions, without any user interaction. The PIPELINE button in the Pipeline widget will do the same (and also the GO button, as usual in GILDAS widgets).

A specific step can be performed by command `PIPELINE StepName`. The available step sequence is ORGANIZE, FIND, SELECT, COMPUTE, COLLECT, APPLY, SHOW, TIME, TABLES, IMAGE, SHOW and ultimately SAVE to remember the parameters used in the processing. `PIPELINE LAST` will repeat the last step (presumably after you changed a control variable !...) while `PIPELINE NEXT` will execute the next one.

## 13.4 Mosaics and other limitations.

**Mosaics:** The pipeline handles mosaics, but with several limitations. First, the data has to fit in memory. This is often the case for NOEMA data, but may not be true for ALMA data. Second, there is no provision to add short spacings: if this is needed, it should be done for each *uv* table prior to using the pipeline. Last, Self-Calibration is ignored for Mosaics, although there could be cases where sufficient S/N is available for this.

**UV table consistency:** Also, the `PIPELINE` is intended for simultaneous observations with a single tuning and single source. Although multiple sources can be handled by using the appropriate file filter, it is recommended to process them in separate sub-directories.

Non simultaneous observations can lead to puzzling inconsistencies, as the self-calibration from one date might be applied to the wrong setup, flagging that data!

# 14 Really Huge Problems

`IMAGER` basically assumes everything fits into memory. This is in general quite fine for NOEMA data. However, for ALMA data, if you are working with a too small computer (such as my laptop, which is otherwise fine), you may be lacking physical memory (RAM, Random Access Memory), and `IMAGER` may become really inefficient by using Virtual Memory instead.

To avoid time losses, `IMAGER` prevents reading UV data whose size exceeds the available RAM, and warns the user if it exceeds half of the RAM. To treat these cases, `IMAGER` provides instead a number of tools that can work sequentially on the data set, instead of loading it in memory all at once.



1. Working by subsets:  
the `READ /RANGE` command allows to select an ensemble of channels from a UV data. If this ensemble is small enough, `IMAGER` can work. At the end the `WRITE /APPEND` and `WRITE /REPLACE` command will allow to put these channels at their proper places in a deconvolved data cube.
2. Working on UV data files:  
Some operations on UV data, like time averaging, separation of line from continuum emission, or self-calibration, and of course, spectral resampling, are best done using all valid channels to avoid losing sensitivity. To allow `IMAGER` to do them even for large data files, most UV-related commands have a `/FILE` option which instructs the command to work from the corresponding data file, instead of the UV buffers. This includes `UV_PREVIEW /FILE`, `UV_BASELINE /FILE`, `UV_FILTER /FILE` and especially the `UV_SPLIT /FILE` commands. Time averaging can be performed by `UV_TIME /FILE`, and prior sorting by time order can be done by `UV_SORT /FILE`. Spectral range extraction is possible by `UV_EXTRACT /FILE`, spectral resampling by `UV_COMPRESS /FILE`, `UV_RESAMPLE /FILE`, and `UV_HANNING /FILE`.

By using the above commands, all operations can be done in a quasi sequential way, avoiding to load in memory whole data sets.

Two commands have no equivalent using the `IMAGER` buffers, and work only on files. Their `/FILE` option is used to provide an homogeneous syntax, but must be present for the command line to be valid.

1. the `UV_MERGE /FILE`  
that allows to merge together an arbitrary number of UV tables, in spectral line (with spectral resampling) or continuum (with flux scaling according to a spectral index) modes.
2. the `UV_SPLIT /FILE`  
that combines the capabilities of `UV_BASELINE` and `UV_FILTER` in a single command, since both operations require the same parameters and provide complementary informations.

The `UV_SORT /FILE` command also has a different behaviour than its memory only version `UV_SORT`. While the latter creates a transposed version of the UV table for internal use (it **cannot** be saved), the former keeps the normal organisation with the visibility axis first.

An example of use of such facilities is the `@ image-mosaic` script that splits the `uv_map` step into chunks that fit in the computer memory available to the user.

## 15 Polarization Handling

**IMAGER** recognizes and handles polarization at different levels. Although support for polarization is basically complete for continuum data, it remains **experimental, and is continuously improving**.

Contact the **IMAGER** authors if you need to analyze Polarized data, using Mail to: `imager-hotline@services.cnrs.fr`

### 15.1 Data Handling

#### Importing data

When importing data, the `fits-to-uv` script assumes by default the data is unpolarized and produces the pseudo-polarisation state "None" from the UVFITS file, by a properly weighted combination of the two parallel hand states if more than one state is present. The weighting is based on the relative noise in both polarization states.

Full polarization information can be preserved by adding the `/STOKES` option to the `@ fits-to-uv` command.

The `READ UV` command will read data with any polarization state(s).

#### Processing data

On the contrary, practically all **IMAGER** commands cannot handle more than 1 polarization state. So far, only two commands fully support polarized data: `UV_TIME` and `STOKES`.

- `STOKES` is the primary command that allows to derive or extract a UV data with only one Stokes parameter from a UV data set with several polarization states. **IMAGER** can then process the individual Stokes parameters separately.
- For convenience (because polarized data is obviously in general bigger), the `UV_TIME` command can be used for time averaging prior to use of the `STOKES` command.
- Most other commands will flatly refuse to handle data with more than 1 polarization state (e.g. `UV_FILTER`, `UV_RESAMPLE`, etc...).
- For debugging purpose, some commands like `UV_PREVIEW`, `UV_MAP` or `UV_STAT` will operate with more than 1 polarization state, but will not produce meaningful results (only a subset of the data may be treated).

Some imaging strategies cannot be used directly on polarized data. Also, the automatic definition of supports (`MASK /THRESHOLD`) only makes sense on Stokes I or parallel hand polarization states, not on Stokes Q,U,V or cross-hand states. The same applies to spectral line identifications.

**PIPELINE processing** The PIPELINE tools does not automatically handle polarization data. However, through judicious use of the `PIPELINE SELECT` and `PIPELINE FIND` commands with ad-hoc filters, imaging, including self-calibration, is possible through custom (though simple) scripts.

The script `self-polar.ima` just does that, and follows the naming conventions used by the `MAP_POLAR` command. It contains the following commands

```
CATALOG                ! No catalog, no Line emission
! "Split the X+Y (XX,YY,XY,YX) UVFITS file into I,Q,U,V Stokes UV tables"
@ stokes-split &1
```

```

! Setup the pipeline
IMAGER\PIPELINE ?
IMAGER\PIPELINE organize      ! " Move UV tables to RAW/"
sic mkdir UVFITS
SIC\SYSTEM " mv *.uvfits UVFITS/"
SIC\SYSTEM " mv RAW/&1.uvt .." ! "Remove the X+Y UV table from RAW/"
!
! Select the I image for self-calibration
let all%filter *-I
IMAGER\PIPELINE select
IMAGER\PIPELINE compute
!
! Apply self-calibration solution to I,Q,U,V data
let all%filter *
IMAGER\PIPELINE find
IMAGER\PIPELINE select
IMAGER\PIPELINE collect
IMAGER\PIPELINE apply
! Image every thing consistently
IMAGER\PIPELINE image
PIPELINE SAVE

```

### Analysing data

The **MAP\_POLAR** command allows to derive images of the Polarized intensity and/or fraction and Polarization angle, as well as display of the polarization vectors onto a background image. So far, the command only works for a single plane image.

The **MAP\_POLAR** command works through data files that follow conventional naming rules to identify them. The implicit rule is that Stokes S (where S is any of I,Q,U,V) is stored in a file of name 'NameBegin'"-N"'NameEnd', e.g. if 'NameBegin' is *My\_Data*

*My\_Data-I+C.uvt, My\_Data-U+C.lmv-clean, etc..*

## 15.2 The STOKES command

The **STOKES** command operates on the current UV buffer, or on files if the **/FILE** option is present. It allows to extract a UV data with visibilities for one output (pseudo-)Stokes parameter from UV data with visibilities with 1,2 or 4 (pseudo-)Stokes parameters. Besides the standard Stokes parameters I, Q, U, V, RR, LL, RL, LR (Left and Right circular), XX, YY, XY and YX (X and Y linear) which are defined in the Sky frame<sup>10</sup>, command **STOKES** recognizes pseudo-Stokes values NONE, HH, VV, HV and VH which are the linear polarization states in the frame of the antennas (Horizontal and Vertical pure states).

Conversion from the H-V pseudo-Stokes polarization states to any standard Stokes parameter is made by the **STOKES** command by applying the rotation due to the parallactic angle. For this, the UV data set must contain the **PARA\_ANGLE** extra column. If it is not present, it can be added

<sup>10</sup>ultimately, a similar DD, SS, DS and SD pseudo-Stokes polarization set may be added for circular polarization. D is the first letter for Dexter, the Latin name for Right, while S is the first letter of Senester, the Latin name for Left.

to the data set by command `UV_ADD /FILE`. That command can also insert the Doppler correction as an extra column.

Script `stokes-split` can be used to split a full polarization UV table in 4 UV tables, one for each IQUV Stokes parameter, following the standard naming convention expected for final image use by `MAP_POLAR`.

## 16 Advanced Data Analysis

Besides basic interferometric imaging, **IMAGER** offers a number of advanced tools that can be used to extract more information from the available data than just by visual inspection of the deconvolved images.

These tools are particularly useful for weak signal detection. Some of them are generic (e.g. the Matched Filtering), others specific of some astrophysical situations (e.g. the **KEPLER** tool)

### 16.1 Matched Filtering

Weak signal detection is always an issue in most astrophysical cases (e.g. high redshift galaxies, faint lines in proto-planetary disks, to cite some).

For spectral lines, **IMAGER** offers the **UV\_DETECT** command, that uses an image model as an optimal filter to enhance weak line detection. This is a generic tool, that can use an observed data cube (from a strong line, presumably) as the image model, or the result of a simulation.

### 16.2 Line Stacking

Another aspect is spectral line stacking, when several lines are assumed to follow the same spatial distribution. This can be done using command **UV\_MERGE /MODE STACK**. The stacked UV table result can be imaged and analyzed as usual. Like **UV\_DETECT**, **UV\_MERGE** does not make any assumption on the source shape.

### 16.3 Rotationally symmetric (thin) structures: Keplerian disks

The **KEPLER** command re-aligns in velocity the spectra as a function of radius (distance from the rotation center), by correcting from the projection effect and radial velocity law. This allows to stack spectra coming from the same radius, and thus to derive radial profiles.

The result is a Position-Velocity image, and can be displayed conveniently with the **SHOW KEPLER** command.

The **KEPLER** command assumes by default that the velocity law is Keplerian. However, arbitrary analytic laws can be used (see **KEPLER /VELOCITY**, so that the tool can also be used for example for spectral lines in galaxies.

### 16.4 Image Handling and Comparison

The **MAP\_\*** suite of commands (**MAP\_COMBINE**, **MAP\_COMPRESS**, **MAP\_INTEGRATE** **MAP\_REPROJECT**, **MAP\_RESAMPLE**, **MAP\_SMOOTH** and **MAP\_CONTINUUM**) allow basic operations on Data Cubes.

Command **COMBINE** simplifies Data cube combinations, by combining individual steps that are otherwise available in **MAP\_REPROJECT**, **MAP\_RESAMPLE**, **MAP\_COMBINE**, while command **VIEW /OVERLAY** allows visual comparison of two data cubes.

## 17 DISPLAY Language Internal Help

### 17.1 Language

DISPLAY\ Language summary

The DISPLAY\ Language contains commands to display data cubes and results in a flexible, interactively controlled or scripted way. Available commands:

CATALOG	: Define the spectral line catalog to identify transitions
COLOR	: Control the color LUT to highlight the Zero level
FIND	! Search for spectral lines in the specified range
LOAD	: Read a file in the DATA area for further display
EXPLORE	: Explore a data cube: make a plot of spectra around a 2-D map
EXTRACT	: Extract a subset from a data cube
INSPECT_3D	: Visualize any data cube by cuts along 3 main directions
POPUP	: Enlarge one panel of a display
SET	: Set some IMAGER or GreG parameter
SHOW	: Display (in a plane by plane plot) any data cube or other results from the IMAGER program.
SLICE	: Extract a Slice of the specified data cube
SPECTRUM	: Compute integrated spectrum from data cube
STATISTIC	: Compute Statistics on specified data
VIEW	: Show (in a comprehensive plot) any data cube

Commands EXPLORE, INSPECT\_3D, SHOW and VIEW remember and share the same input data for their display (e.g. SHOW CLEAN, followed by EXPLORE will work as EXPLORE CLEAN).

### 17.2 CATALOG

[DISPLAY\]CATALOG [FileName [... [FileNameN]]]

Define or list the current catalog(s) for spectral line identification. A catalog is a file in the "Astro" GILDAS format, as used in programs ASTRO or CLASS in the GILDAS suite, or in the LINEDB data format. Without argument, or with argument ?, the command will just list the names of the current catalog(s).

There can be only ONE Astro catalog connected at a time, and it is exclusive of any LINEDB data bases. On the opposite, there may be several LINEDB data bases specified by the CATALOG command.

At initialization, IMAGER search for \$HOME/imager.linedb as default catalog, then gag\_data:imager.linedb if not found. If the specified catalog does not exist, no spectral line identification will be done.

Direct use of the LINEDB\USE command is also possible to define the

LINEDB catalog(s), though this is not recommended (possible conflicts with an Astro catalog).

### 17.2.1 CATALOG Default

A default catalog can be created (in the local directory) by executing once

```
@ gag_data:imager-linedb.sic
```

This may take a while, and even get stuck occasionally because it performs network access to remote databases. You can later copy this catalog to your \$HOME. See `HELP LINEDB\` to add or remove species from such catalogs.

### 17.2.2 CATALOG Astro

The ASTRO catalog format is one of the two following ones:

A comma separated value file, including the frequency in MHz, the species name, and the transition name, e.g.:

```
150E3; MOLE; TRANSITION;
```

A list-directed file, with the same information, e.g.:

```
150E3 'MOLE' 'TRANSITION'
```

Lines beginning with an exclamation mark are considered as comments. The first line **\*\*MUST\*\*** be a comment line.

A default catalog (with no implied warranty) is given in `gag_data:molecules.dat`.

### 17.2.3 CATALOG Linedb

The LINEDB catalog format is a more flexible facility, which can also holds additional information. On-line spectral databases (JPL and CDMS) are directly useable as LINEDB catalogs, although access can be long in this case.

Scripts named `gag_data:*-linedb.sic` are available as examples to construct local data bases from the on-line ones. Beware that the on-line databases sometimes change their naming conventions, so that identifying a given species by name can be tricky.

In 2020, access to CDMS was unreliable. It has improved since. Access to JPL is operational, but frequencies are not as up-to-date as in CDMS.

Local files in the JPL ".cat" format can be used, but as of Jan-2020, the Einstein coefficients are wrong. They also require a "partfunc.cat" in the following format (given here for HN-15-C as an example)

species HN-15-C 28006

temperatures 300. 225. 150. 75. 37.5 18.75 9.375

qpart 141.06 105.9 70.797 35.514 17.23 9.135 4.746

The tag number (28006 here) must match that of the ".cat" file.

#### 17.2.4 CATALOG LINEDB%ENERGY

Maximum energy of the upper state of the selected transitions, in K. This applies only to LINEDB data bases.

### 17.3 COLOR

[DISPLAY\]COLOR HueRange [HueZero HueExtent]

Select a color Look-up-Table so that the color at value Zero is given by HueZero (in range [0,360[), and the overall HUE extent is HueExtent (which can be larger than 360). HueRange (in the same units) indicate a part of the LUT which becomes progressively whiter (less saturation, HueRange < 0) or darker (less intensity, HueRange > 0) around the colour HueZero.

Such LUTs allow to outline the Signal-containing regions compared to the noise level, either in bright (HueRange < 0) or dark (HueRange > 0) modes.

### 17.4 EXPLORE

[DISPLAY\]EXPLORE [DataCube] [/ADD Cx Cy [Box]] [/NOPAUSE]

Create a plot with a 2-D map in the middle, and up to 8 spectra around it.

DataCube is the name of an internal 3-D buffer, SIC variable or data file. The 2-D map will be either a channel of this 3-D data set, or a velocity integrated map obtained from it. It will displayed at the center of the plot. If not present, argument DataCube keeps its previous value.



Spectra can be displayed around, with arrows showing their position in the map, either interactively (when the /NOPAUSE option is not present), or manually through the /ADD option. In interactive mode, the user can press S to extract and display the spectrum from any place in the 2-D map.

EXPLORE ? will list the control variables for this command. The usual SIZE and CENTER control the 2-D map size, RANGE controls the velocity range, and SCALE the spectral flux range.

#### 17.4.1 EXPLORE /ADD

```
[DISPLAY\]EXPLORE /ADD Cx Cy [Box]
```

Add the spectrum coming from position Cx Cy (in arcsec) in the specified Box number. The Box number indicates the placement as in a numeric keypad layout. Box 5 (the center) is reserved for the 2-D map.

If Box is not present, the spectrum is placed in the most plausible position according to the coordinates (Cx,Cy).

#### 17.4.2 EXPLORE /NOPAUSE

```
[DISPLAY\]EXPLORE [DataCube] /NOPAUSE
```

Just display the 2-D map and any already existing spectra, but do not call the cursor.

#### 17.4.3 EXPLORE Variables:

Like SHOW, VIEW and INSPECT\_3D, EXPLORE is controlled by variables. Most of them are among those controlling SHOW:

SPAN, RANGE, SIZE, CENTER, SCALE, SPACING, DO\_BIT DO\_GREY, DO\_CONTOUR, DO\_MASK.

In addition, the SFLUX variables controls the displayed flux scale in the map.

#### 17.4.4 CENTER

```
REAL CENTER[2]
```

Specify the relative coordinates of the center of the displayed region,

in `ANGLE_UNIT` defined by `SET ANGLE_UNIT` command.

#### 17.4.5 `DO_BIT`

LOGICAL `DO_BIT`

Show a bitmap color plot (YES) or do not (NO) for each panel. The bitmap range is controlled by variable `SCALE`.

#### 17.4.6 `DO_CONTOUR`

LOGICAL `DO_CONTOUR`

Draw (YES) or do not (NO) draw the contour level, which are controlled by `SPACING` and `SPACE_TYPE`. This is provided for compatibility with Mapping and Greg.

#### 17.4.7 `DO_GREY`

LOGICAL `DO_GREY`

Do (YES) or do not (NO) use grey-scale contouring. Note that this is independent of `DO_CONTOUR`.

#### 17.4.8 `DO_MASK`

LOGICAL `DO_MASK`

Hide part of the plot (contour or bitmaps, and even axis ticks) that lie in the upper left corner of each panel to have a clean display of the value specified by `MARK`.

#### 17.4.9 `RANGE`

REAL `RANGE[2]`

Specify the range to be displayed for the 3rd axis, as well as the displayed range of the integrated spectrum.

`RANGE` should not be confused with `SPAN`, which specifies the displayed velocity range in the two PV diagram panels.

2 SFLUX

Character\*32 SFLUX

Specify the flux (intensity) range for the spectra. SFLUX can be \* or 0 to indicate a fully automatic scale, or indicate a Min Max, each of which possible \* to indicate a automatic limit.

#### 17.4.10 SIZE

REAL SIZE[2]

Specify the displayed are size, in ANGLE\_UNIT (see SET ANGLE\_UNIT command).

#### 17.4.11 SCALE

REAL SCALE[2]

SCALE indicates the Colour Scale Range, range of image units which are displayed in the color bitmap. SCALE = 0 implies an automatic evaluation of this range, based on the Min and Max of the data cube.

#### 17.4.12 SPACE\_TYPE

CHARACTER SPACE\_TYPE

Define the type of spacing for the contour levels

LIN	Linear spacings. The Zero contour is always omitted.
LOG	Exponential spacing
NONE	No contour levels at all (same as DO_CONTOUR = NO)
USER	Keep the contour levels specified by command LEVELS

For LOG case, see HELP LEVELS EXPO in the GreG internal help.

As a backward compatibility, a negative spacing is a convention to use the current contour levels, although using SPACE\_TYPE = USER should be preferred.

#### 17.4.13 SPACING

CHARACTER\*16 SPACING[2]

SPACING indicates the step (and implicitly the contour levels) for contouring and/or greyscale. SPACING[1] control the values, and SPACING[2] the Unit of these values. It can be UNITS (default data cube units), NOISE or SIGMA (noise level), Jy (which also stands for Jy/Beam) and its sub-units mJy (or milliJy) and microJy, or K and its sub-units mK (or

milliK) or microK.

Jy (and its sub-units) is taken as equivalent to Jy/Beam, and automatic conversion between brightness unit (K) and flux unit (Jy/Beam) is made when the data cube has a specified angular resolution and frequency.

SPACING[1] = 0 means an automatic guess of the contours from the Min and Max of the data cube.

The type of spacing is controlled by variable SPACE\_TYPE.

#### 17.4.14 SPAN

REAL SPAN[2]

For EXPLORE, SPAN indicates the limits of plot for the spectra.

### 17.5 EXTRACT

[DISPLAY\]EXTRACT VarName [blc1 blc2 blc3 trc1 trc2 trc3]

Extract a subset of the image variable VarName and put it in the EXTRACTED image variable.

Without argument, the region covered by the subset is defined by the SIZE, CENTER and RANGE values. In this case, the EXTRACTED variable dimensions are automatically derived from this values, and EXTRACTED can be bigger than the actual cube defined by VarName. Areas not covered by the initial VarName are filled out with the Blanking value of the VarName, or by zeros if VarName has no blanking.

If the arguments blc1 to trc3 are specified, the subset corresponds to VarName[blc1:trc1,blc2:trc2,blc3:trc3] of the image variable VarName. The BLCi and TRCi values must correspond to a valid subset.

### 17.6 FIND

[DISPLAY\]FIND Fmin Fmax [/SPECIES Name]

Select spectral lines in the range Fmin to Fmax (in MHz) and return them in the LINES% structure.

LINES%SPECIES contains the name of the species for each line. LINES%FREQUENCY holds its frequency in MHz. LINES%LINES contains the full line names, including the transition. LINES%PLOT contains the

string to be used in graphic display, with codes for superscripts and subscripts when needed.

The sign of `LINES%N` encodes the number of selected lines and type of catalog which was used.

The rest of the structure depends on the catalog type.

If the catalog is in the `ASTRO` format, `LINES%N` is negative and contains the opposite of the number of lines.

If the catalog is in the `LINEDB` format (see `HELP LINEDB\` for details), `LINE%N` is positive and contains the number of selected lines. Quantum numbers, energy levels and line strengths are also available in this case, allowing a more precise selection.

### 17.6.1 `FIND /SPECIES`

```
[DISPLAY\]FIND Fmin Fmax /SPECIES Name
```

Only select lines from species that match the specified `Name`. Only one `Name` can be specified, and the match is case sensitive. There is (limited) support for wildcard so far.

## 17.7 `INSPECT_3D`

```
[DISPLAY\]INSPECT_3D [Argument [FirstPlane [LastPlane]]]
```

where

`Argument`

is the name of a 3-D internal buffer to be plotted (`BEAM`, `CCT`, `CLEAN`, `DIRTY`, `FIELDS`, `MASK`, etc.), or any `Sic Image` variable, or a file name. If not present, `Argument` falls back to the last argument used in `EXPLORE`, `INSPECT_3D`, `SHOW`, or `VIEW` commands.

Simultaneously display cuts along each of main cube directions, as well as the current spectrum. Coordinates are controlled by the cursor position in the plots.

### 17.7.1 `INSPECT_3D` History

`INSPECT_3D` is a command similar to `GO 3VIEW` in `Mapping`, but with a simpler syntax and the ability to display program buffers as well as files.

### 17.7.2 INSPECT\_3D Variables:

Like SHOW, VIEW and EXPLORE, INSPECT\_3D is controlled by variables, selected among those controlling SHOW:

SPAN, RANGE, SIZE, CENTER and CROSS.

### 17.7.3 SPAN

REAL SPAN[2]

SPAN indicates the limits of 2-D plot along the velocity axis, while RANGE indicates the 3rd axis range that is displayed in the integrated spectrum. The spatial dimension (if any is displayed) is controlled by SIZE and CENTER.

If SPAN is 0, it defaults to RANGE. If RANGE is zero, all planes/channels are displayed.

## 17.8 LOAD

[DISPLAY\]LOAD File [/FREQUENCY NewFreq] [/PLANES Start End] [/RANGE Start End Type]

Read the specified File (GILDAS or FITS data cube) into the DATA buffer, for further display.

### 17.8.1 LOAD /FREQUENCY

[DISPLAY\]LOAD File /FREQUENCY RestFreq [/RANGE Min Max Type]

Read the file into the DATA area and reset the velocity scale to the corresponding rest frequencies. Velocities specified in the /RANGE Min Max VELOCITY option would then refer to this new frequency.

### 17.8.2 LOAD /PLANES

[DISPLAY\]LOAD File /PLANES Min Max

Read only the last axis "planes" between the First and Last implied by Min and Max. For an LMV-ordered cube, this would be equivalent to

LOAD File /RANGE Min Max CHANNEL

However, for transposed data cubes, VML or LVM-ordered for example, this

is not true at all when a Frequency/Velocity axis is present: /RANGE would specify a subset of that axis, while /PLANES always indicate a subset of the 3rd axis of the cube.

Min and Max indicate offsets from Plane 1 and the number of planes Nplane. Thus Max can be negative: it then indicates Last = Nplane-Max. Also Min=0 and Max=0 implies loading all the channels.

### 17.8.3 LOAD /RANGE

[DISPLAY\]LOAD File /RANGE Min Max Type

Load only the channels between the First and Last defined by Min Max and Type. Type can be CHANNEL, VELOCITY or FREQUENCY. If the Data cube has no Frequency/Velocity axis, only CHANNEL is allowed.

For type CHANNEL, Min and Max indicate offsets from Channel 1 and Channel Nchan (the number of channels in the data set). Thus Max can be negative: it then indicates Last = Nchan-Max. Also Min=0 and Max=0 implies loading all the channels.

The /RANGE option is not (yet) allowed for FITS files.

## 17.9 POPUP

DISPLAY\POPUP [Number]

POPUP allows to "pop up" a single plane display out of a multi-box plot. The action driven by POPUP depends on the content of the whole plot.

After a SHOW command, POPUP will call the cursor, and any key stroke (except E to EXIT the loop) will display the corresponding sub-plot in a separate window. The sub-plot may contain an single plane display, a spectrum, a cumulative flux, the phase or amplitude correction from a SELF CAL, etc...

POPUP Number will popup the specified panel number (counted from Top Left Corner down to Bottom Right corner).

POPUP will have no action if the display was not created by SHOW.

### 17.10 SET

[DISPLAY\]SET KeyWord [Value [...]] [/DEFAULT]

Set an IMAGER or GREG internal value. The only current possible keyword for IMAGER is ANGLE\_UNIT. Use HELP GREG\SET for help on the Greg keywords. This command has no impact on axes that are in Angles.

### 17.10.1 SET ANGLE\_UNIT

[DISPLAY\]SET ANGLE\_UNIT [Degree|Minute|Second|Radian|ABSOLUTE|RELATIVE]

List or Specify the angular unit and mode used for box labelling. The mode can be ABSOLUTE to use sexagesimal notation in Hour - Degree for Right Ascension and Declination, or RELATIVE to label with offsets in the current angle unit.

SET ANGLE\_UNIT

will list the current and fallback units (if any)

SET ANGLE\_UNIT ABSOLUTE|RELATIVE

will toggle between ABSOLUTE labels and relative ones in the current angular unit. ABSOLUTE labeling is not possible if there is a rotation angle in the images: only relative labels are used in this case, whatever the mode specified by SET ANGLE\_UNIT.

SET ANGLE\_UNIT Degree|Minute|Second|Radian

will set the current angle unit to the specified value, and enforce use of offset labels in the specified unit.

### 17.10.2 SET OtherKeyword

[DISPLAY\]SET OtherKeyword [Value ...]

If the SET argument is not recognized, the command falls back to the GREG\SET command. See HELP GREG\SET for possibilities.

## 17.11 SHOW

[DISPLAY\]SHOW Argument [Arg1 [Arg2]] [/SIDE]

where

Argument

is a Keyword (e.g. COVERAGE, NOISE, UV\_FIT or MOMENTS), the name of an internal buffer to be plotted (BEAM, CCT, CLEAN, DIRTY, etc..), a 2-D or 3-D SIC image variable or datacube filename (in Gildas or simple FITS image format).

[DISPLAY\]SHOW ?



will list the names of recognized keywords and buffers.

Except for UV data where they have a different meaning,  
Arg1 and Arg2

are optional arguments to restrict the range of channels to be plotted. They default to FIRST and LAST variable values respectively, and Arg2 defaults to Arg1 if only Arg1 is specified.

The UV data in the internal buffer is the one loaded by command READ UV File and optionally resampled by UV\_RESAMPLE, UV\_COMPRESS, etc..., or transformed by UV\_CONTINUUM. Flagged UV data will appear in a different color.

Command VIEW offers a different style of display for cubes, NOISE and CCT. Command INSPECT\_3D offers another style for cubes.

### 17.11.1 SHOW /SIDE

[DISPLAY\]SHOW Argument [FirstPlane [LastPlane]] /SIDE

Add the <V SIDE display of coordinates and values like in the VIEW command, and loop on the Graphic cursor to explore the data.

This will be the default mode if variable SHOW\_SIDE is set to YES.

### 17.11.2 SHOW History

SHOW derives from the GO PLOT script available in GreG and Mapping. GO PLOT (or its variants GO BIT, GO NICE and GO MAP) and GO UVSHOW offered similar features to those of SHOW, but take data from files or SIC image variables, depending on variables NAME and TYPE.

### 17.11.3 SHOW Keywords:

SHOW recognizes the following keywords

BEAM	Synthesized beam(s)
CCT	Clean Cumulative Flux
COMPOSITE	Moments + Flux
COVERAGE	UV Coverage
FLUX	Integrated spectra over defined regions
KEPLER	Radial profile and PV diagram of a Keplerian disk
MOMENTS	0th,1st,2nd moments + peak value
NOISE	per channel noise
PRIMARY	Primary beam(s)
PV	Position-Velocity plot

SED	Spectral Energy Distribution
SELFAL	Self-Calibration corrections
SPECTRA	Spectra on a 2-D map-like grid
SOURCES	Clean component positions
UV	UV data
UV_FIT	Results of the UV_FIT command

SHOW calls the appropriate procedures for each action

p_show_map	for data cubes
p_show_beam	for BEAM and PRIMARY cubes
p_show_cct	for CCT (Clean Component Tables)
p_show_composite	for Composite display (Moments + Flux)
p_show_flux	for FLUX
p_show_moments	for MOMENTS
p_show_noise	for NOISE
p_lmv_map	for PV
p_show_sed	for SED
p_show_selfcal	for SELFAL
p_show_tcc	for SOURCES (Clean Component Positions)
p_spectra	for SPECTRA
p_uvshow_sub	for UV_DATA data
p_plotfit	for UV_FIT data (UV_FIT results)

#### 17.11.4 BEAM

SHOW BEAM [PLANE|FIELD Kn] [First Last]

Show some sub-cube of the (up to 4-D) dirty Beam.

The 2nd argument indicates whether SHOW shows all Fields for a given frequency plane (PLANE keyword), or all Frequency-dependent beams for a given Field. The 2nd and 3rd arguments are optional if the beam is only 3-D, which occurs for a single field or a frequency-independent beam in Mosaics (narrow band approximation).

#### 17.11.5 CCT

SHOW CCT

Display the Cumulative Clean Flux as function of component number. Pretty useful to see if CLEAN has reasonably converged.

#### 17.11.6 COMPOSITE

SHOW COMPOSITE

Display the 3 "moments" images derived from a datacube by command MOMENTS, and the integrated line flux computed by command FLUX. The contour spacing for each image is controlled by its own variable:

AREA\_SPACING for the integrated area M\_AREA  
VELO\_SPACING for the Velocity field M\_VELO (in km/s)  
WIDTH\_SPACING for the Width field M\_WIDTH (in km/s)

As for other image displays, CENTER and SIZE control the center and size of the image (in arcsec). Limits for the Flux spectrum are computed automatically.

#### 17.11.7 CONTINUUM

SHOW CONTINUUM

Display the "continuum" map, i.e. the map obtained by UV\_MAP /CONTINUUM and CLEAN.

#### 17.11.8 COVERAGE

SHOW COVERAGE [Ant [Date]]

Displays the UV coverage. Ant and Date are optional arguments indicating which Antenna is to be highlighted, and for which date. Date is a sequential number from 1 to the number of observing dates.

For spectral line UV data, SHOW COVERAGE will only show one UV coverage if FIRST and LAST are set to zero. It will show one per channel otherwise.

#### 17.11.9 FIELDS

SHOW FIELDS

Display the positions of the fields in a Mosaic, by a circle at the half-power primary beam size.

#### 17.11.10 FLUX

SHOW FLUX

Displays the integrated spectra in all regions used by command FLUX.

**17.11.11 KEPLER**

SHOW KEPLER [All|BOth|PV|PProfile|SPectrum]

Displays the results of the KEPLER command, which can be

PV	Position (radius) Velocity plot
PProfile	Peak intensity radial profile
SPectrum	Integrated spectrum
BOth	Radial Profile and Integrated spectrum
All	All of the above

Other combinations are allowed using the KEPLER\_SHOW%PROF, KEPLER\_SHOW%PV and KEPLER\_SHOW%SPEX variables.

Display ranges are controlled by variables KEPLER\_SHOW%X, where X = V for the velocity range, X = T for the temperature profile range, X = R for the radius range, and X = F for the integrated flux range.

**17.11.12 MOMENTS**

SHOW MOMENTS

Display the 4 "moments" images derived from a datacube by command MOMENTS. The contour spacing for each image is controlled by its own variable:

AREA_SPACING	for the integrated area M_AREA
PEAK_SPACING	for the peak brightness value M_PEAK (in K)
VELO_SPACING	for the Velocity field M_VELO (in km/s)
WIDTH_SPACING	for the Width field M_WIDTH (in km/s)

As for other image displays, CENTER and SIZE control the center and size of the image (in arcsec).

**17.11.13 NOISE**

SHOW NOISE [CLEAN|DIRTY]

Compute and display the noise statistic of the specified data cube, using a Gaussian fit to the histogram of pixel intensities for each channel.

**17.11.14 PRIMARY**

SHOW PRIMARY [PLANE|FIELD Kn] [First Last]

Show some sub-cube of the (4-D) Primary Beams.

The 2nd argument indicates whether SHOW shows all Fields for a given frequency plane (PLANE keyword), or all Frequency-dependent beams for a given Field (FIELD keyword). The 2nd and 3rd arguments are optional if the beam is only 3-D, which occurs for a single field or a frequency-independent beam in Mosaics (narrow band approximation).

#### 17.11.15 PV

SHOW PV [[CLEAN|DIRTY|SKY] Axis Offset]

Extract from the indicated data cube a Position-Velocity image at the specified Offset (in arcsec) along the specified Axis (X or Y), and display it.

The data cube name is optional: the last specified one is used by default.

will simply redisplay (with different controls, see SHOW PV ? to have a list) the last extracted Position-Velocity image.

#### 17.11.16 SED

SHOW SED [Frequency [FileName]]

Display the SED, computed by the "SED" widget from images (using the FLUX command) or from UV Tables (by fitting a simple model using UV\_FIT), and fit a simple power law model through it.

Frequency is the reference frequency in GHz at which the flux is computed.

FileName is the data file produced by the "SED" widget.

If Frequency or Filename are not specified, their last values are re-used.

#### 17.11.17 SELFCAL

See HELP SELFCAL SHOW, and/or use SHOW SELFCAL ?

### 17.11.18 SNR

SHOW SNR

Display the Signal to Noise ratio map of a Mosaic.

### 17.11.19 SOURCES

SHOW SOURCES [First [Last]]

Display the "point sources" found by CLEAN at their positions, using a marker with area proportional to their flux. Positive sources are in black, negative ones are in red.

The displayed zone is controlled by variables SIZE and CENTER, as for in SHOW CLEAN or SHOW DIRTY. However, when SIZE is 0, the displayed zone is set to the minimum required to display all point sources detected by CLEAN. It may thus differ from the CLEAN map size.

### 17.11.20 SPECTRA

SHOW SPECTRA Clean|Dirty|Sky|ImageVar

Display individual spectra in a Map-like display (one per box, placed at their respective positions) from a 3-D SIC variable, assumed to be in the LMV order.

Note: the second argument may be omitted to re-display the same dataset with different control parameters. SHOW SPECTRA is however not fully protected against changes in the data set between two invocations, so this should only be used for consecutive commands.

### 17.11.21 UV\_DATA

SHOW UV\_DATA [Ant [Date]]  
SHOW UV [Ant [Date]]

Displays the UV data. Items to be displayed are controlled by XTYPE and YTYPE variables. Ant and Date are optional arguments indicating which Antenna is to be highlighted, and for which date. Date is a sequential number from 1 to the number of observing dates.

Structure uvshow% controls some additional options, such as coloring of various dates, of data flagging, etc...

**17.11.22 UV\_FIT**

SHOW UV\_FIT [ ? | RESET ]

Display the UV\_FIT results. The display is controlled by the UVF% structure.

SHOW UV\_FIT ? will list the current values of these control parameters.

SHOW UV\_FIT RESET will reset all control variables (UVF% structure) to their default values.

The number and order of the fitted functions to be plotted are controlled by UVFIT%NF and UVFIT%ORDER

The number of parameters to be plotted along X and Y axes are controlled by UVFIT%NX, UVFIT%NY. The kinds and ranges of those parameters are coded in the UVFIT%XTYPE and UVFIT%YTYPE strings (e.g. kind min max). Possible kinds are: CHANNEL VELO FREQ RMS RA DEC FLUX WIDTH MAJOR MINOR ANGLE and RATIO. A \* instead of min and/or max implies the use of the default minimum and maximum values of the plotted parameter.

**17.11.23 Variables:**

SHOW Image control variables

The following variables control the SHOW display.

Display the header	DO_HEADER	[ YES ]	
Display a color wedge	DO_WEDGE	[ YES ]	
Plot bitmaps	DO_BIT	[ YES ]	
Add the clean beam	DO_NICE	[ NO ]	
Add the UV coverage	DO_COVERAGE	[ NO ]	
Add the dirty beam	DO_DIRTY	[ NO ]	
Display the labels	DO_LABEL	[ YES ]	
Display contour levels	DO_CONTOUR	[ YES ]	
grey-scale contours	DO_GREY	[ NO ]	
Better marks	DO_MASK	[ NO ]	(Hide image behind cha
Channel range	RANGE	[ 0 0 ]	in 3rd axis unit, (0,0)
Channel label	MARK	[ velocity ]	[VELOCITY, FREQUENCY or
Displayed field size	SIZE	[ 0 0 ]	in ANGLE_UNIT
Field center	CENTER	[ 0 0 ]	offset in ANGLE_UNIT
Cross size at center	CROSS	[ 2 ]	in arcsec, 0 ==> none
Fields layout	DO_FIELDS	[ NO ]	(for Mosaics)
Colour Scale range	SCALE	[ 0 0 ]	(0,0) ==> all dynamic

Contour levels	SPACING	[ 0 Units]	(0) => Guess
Spacing type	SPACE_TYPE	[ AUTO]	[LIN, LOG or USER]
Side Display	SHOW_SIDE	[ NO ]	

#### 17.11.24 BOX\_LIMITS

CHARACTER\*60 BOX\_LIMITS

If not void, this character string must indicate the 4 limits of each panel display, for example

```
LET BOX_LIMITS "* * -5 10"
```

If void, variables SIZE and CENTER are used instead.

#### 17.11.25 DO\_BIT

LOGICAL DO\_BIT

Show a bitmap color plot (YES) or do not (NO) for each panel. The bitmap range is controlled by variable SCALE.

#### 17.11.26 DO\_CONTOUR

LOGICAL DO\_CONTOUR

Draw (YES) or do not (NO) draw the contour level, which are controlled by SPACING and SPACE\_TYPE. This is provided for compatibility with Mapping and Greg.

#### 17.11.27 DO\_COVERAGE

LOGICAL DO\_COVERAGE

For SHOW DIRTY or SHOW CLEAN, DO\_COVERAGE indicates if in addition to the channel maps, the UV coverage should be displayed in another panel.

#### 17.11.28 DO\_DIRTY

LOGICAL DO\_DIRTY

For SHOW DIRTY or SHOW CLEAN, DO\_DIRTY indicates if in addition to the channel maps, the dirty beam should be displayed in another panel.



**17.11.29 DO\_FIELDS**

LOGICAL DO\_FIELDS

Plot the 50 % contour levels of the individual pointings in a Mosaic on top of the maps.

**17.11.30 DO\_GREY**

LOGICAL DO\_GREY

Do (YES) or do not (NO) use grey-scale contouring. Note that this is independent of DO\_CONTOUR.

**17.11.31 DO\_HEADER**

LOGICAL DO\_HEADER

DO\_HEADER indicates whether a panel displaying a summary information about the displayed data is drawn or not.

**17.11.32 DO\_LABEL**

LOGICAL DO\_LABEL

DO\_LABEL indicates if the axes should be labelled.

**17.11.33 DO\_MASK**

LOGICAL DO\_MASK

Hide part of the plot (contour or bitmaps, and even axis ticks) that lie in the upper left corner of each panel to have a clean display of the value specified by MARK.

**17.11.34 DO\_NICE**

LOGICAL DO\_NICE

DO\_NICE indicates if the angular resolution of the data ("beam") should be displayed in the lower left corner of each panel.

**17.11.35 DO\_WEDGE**

LOGICAL DO\_WEDGE

DO\_WEDGE indicates whether a color wedge of the bitmaps is drawn or not. It appears in the Header panel, so DO\_WEDGE is active only if DO\_HEADER and DO\_BIT are set.

**17.11.36 CENTER**

REAL CENTER[2]

Specify the relative coordinates of the center of the displayed region, in ANGLE\_UNIT (as specified by SET ANGLE\_UNIT).

**17.11.37 CROSS**

REAL CROSS

Indicate the size (in arcsec) of a cross to be drawn at the map projection center, as a reference marker for relative positions.

**17.11.38 MARK**

CHARACTER\*12 MARK

Specify the type of labelling for each panel. It can be VELOCITY, FREQUENCY or CHANNEL. Case is not significant.

**17.11.39 RANGE**

REAL RANGE[2]

Specify the range (in 3rd axis unit) of displayed channels. This provides a facility similar to FIRST and LAST variables, but in a more user-oriented unit.

RANGE should not be confused with SPAN, which specifies the displayed velocity range when one of the 2 first axis is of type Velocity, e.g. for SHOW PV

**17.11.40 SCALE**

REAL SCALE[2]

SCALE indicates the Colour Scale Range, range of image units which are displayed in the color bitmap. SCALE = 0 implies an automatic evaluation of this range, based on the Min and Max of the data cube.

#### 17.11.41 SIZE

REAL SIZE[2]

Specify the displayed are size, in ANGLE\_UNIT.

#### 17.11.42 SPACE\_TYPE

CHARACTER SPACE\_TYPE

Define the type of spacing for the contour levels

LIN        Linear spacings. The Zero contour is always omitted.

LOG        Exponential spacing

NONE       No contour levels at all (same as DO\_CONTOUR = NO)

USER       Keep the contour levels specified by command LEVELS

For LOG case, see HELP LEVELS EXPO in the GreG internal help.

As a backward compatibility, a negative spacing is a convention to use the current contour levels, although using SPACE\_TYPE = USER should be preferred.

#### 17.11.43 SPACING

CHARACTER\*16 SPACING[2]

SPACING indicates the step (and implicitly the contour levels) for contouring and/or greyscale. SPACING[1] control the values, and SPACING[2] the Unit of these values. It can be UNITS (default data cube units), NOISE or SIGMA (noise level), Jy (which also stands for Jy/Beam) and its sub-units mJy (or milliJy) and microJy, or K and its sub-units mK (or milliK) or microK.

Jy (and its sub-units) is taken as equivalent to Jy/Beam, and automatic conversion between brightness unit (K) and flux unit (Jy/Beam) is made when the data cube has a specified angular resolution and frequency.

SPACING[1] = 0 means an automatic guess of the contours from the Min and Max of the data cube.

The type of spacing is controlled by variable SPACE\_TYPE.

#### 17.11.44 SPAN

REAL SPAN[2]

SPAN indicates the limits of plot along the velocity axis, when one of the plotted dimensions is Velocity. In particular, SPAN is used for SHOW PV. The spatial dimension (if any is displayed) is controlled by SIZE and CENTER.

Note that SPAN differs from RANGE: RANGE controls the range of planes displayed for a 3-D cube.

#### 17.11.45 SHOW\_SIDE

LOGICAL SHOW\_SIDE

Controls whether the Side Display is active by default or not.  
Option /SIDE can be used to overcome this default value.

### 17.12 SLICE

[DISPLAY\]SLICE VarName Start1 Start2 End1 End2 UNIT

Cut a slice through the 3-D image variable VarName with the specified edges and put it in the SLICED image variable. UNIT is a keyword indicating in which units the edges are specified. It can be PIXELS, DEGREE, MINUTE, SECOND, RADIAN, or ABSOLUTE. For ABSOLUTE, Start1 and End1 are assumed to be in hours and Start2 End2 in degrees, with sexagesimal notation allowed.

[DISPLAY\]SLICE VarName StartX StartY Unit ANGLE AngleValue

This alternate syntax allows to specify a point and an orientation of the slice. The coordinates StartX StartY are in the angular unit specified by Unit (which can be ABSOLUTE) AngleValue is in Degree. The Slice length will be automatically computed to intersect the whole cube. This syntax can be more convenient to compare parallel slices, or slice intersecting at a common point that can be specified by StartX StartY.

### 17.13 SPECTRUM

[DISPLAY\]SPECTRUM OutSpec InCube [Mask]

[/CORNER Imin Imax Jmin Jmax] [/PLANE First Last] /MEAN or /SUM

Compute a Spectrum, stored in variable OutSpec from an input data cube stored in variable InCube, by summing (if /SUM is present) or averaging (if /MEAN is present) over the region specified by the current GreG polygon, or the 2-D or 3-D mask specified by Mask, truncated to the specified corner if any.

OutSpec[1] contains the "velocities" (values along the 3rd axis of the InCube data cube). OutSpec[2] contains the spectrum values.

### 17.13.1 SPECTRUM /CORNER

```
[DISPLAY\]SPECTRUM OutSpec InCube [Mask] /CORNER Imin Imax Jmin Jmax  
[/PLANE First Last] /MEAN or /SUM
```

Restricts the computation to the specified 2-D region of the data cube. One of the mutually exclusive options /MEAN or /SUM must be present.

### 17.13.2 SPECTRUM /MEAN

```
[DISPLAY\]SPECTRUM OutSpec InCube [Mask] /MEAN  
[/CORNER Imin Imax Jmin Jmax] [/PLANE First Last]
```

Indicates that we are computing a Mean spectrum.  
The spectrum is the average spectrum accounting for all valid pixels defined by the selection.

/MEAN is exclusive of /SUM.

### 17.13.3 SPECTRUM /PLANE

```
[DISPLAY\]SPECTRUM OutSpec InCube [Mask] /PLANE First Last  
[/CORNER Imin Imax Jmin Jmax] /MEAN or /SUM
```

Restricts the spectrum to the specified channels of the data cube. One of the mutually exclusive options /MEAN or /SUM must be present.

### 17.13.4 SPECTRUM /SUM

```
[DISPLAY\]SPECTRUM OutSpec InCube [Mask] /SUM  
[/CORNER Imin Imax Jmin Jmax] [/PLANE First Last]
```

Indicates that we are computing an integrated spectrum. The result corresponds to the integral of the signal over the valid area (sum of

values times the pixel size in user units).

/SUM is typically used to compute integrated flux from Jy/Beam units. /SUM is exclusive of /MEAN.

## 17.14 STATISTIC

```
[DISPLAY\]STATISTIC [DataCube [FirstPlane [LastPlane]]
[/EDGE Margin] [/NOISE VarNoise]
```

Compute some basic statistics (min, max, mean, rms,...) on the specified DataCube buffer (default: CLEAN) and planes (default: variables FIRST and LAST). The current polygon or mask (see commands SUPPORT and MASK) is used to define the area on which the pixels are to be taken into account, except when /EDGE 0 is mentioned.

In addition to Min and Max, the command prints 3 noise numbers:

- the rms inside the current support (whose value depends on the source strength and structure)
- the rms outside of the support (a good estimate of the effective noise), returned in variable STAT\_NOISE.
- the theoretical thermal noise (that would be the expected noise unless the data is dynamic range limited, or unless the weights were not set properly)

Caution: Statistics on primary-beam corrected images (SKY) cannot be properly computed in this way, because the noise is non uniform.

### 17.14.1 STATISTIC /NOISE

```
[DISPLAY\]STATISTIC [DataCube [FirstPlane [LastPlane]]
[/EDGE Margin] /NOISE VarNoise
```

Return the rms noise in the specified VarNoise SIC real scalar variable. The rms noise is also available in variable STAT\_NOISE, and if the image is the CLEAN image, in CLEAN%NOISE as well for further convenience and use in scripts.

### 17.14.2 STATISTIC /EDGE

```
[DISPLAY\]STATISTIC [DataCube [FirstPlane [LastPlane]]
/EDGE Margin [/NOISE VarNoise]
```

Define the size of the "edges" that are avoided in the statistic estimate. Margin is a number in range [0,0.5[ . Default is 1/16.

Margin 0 means considering the whole image, ignoring mask and supports.

### 17.15 VIEW

```
[DISPLAY\]VIEW Argument [FirstPlane [LastPlane]] [/NOPAUSE] [/OVER-
LAY]
```

where (in the most general case, see details for specific Keywords)

is the the name of an internal buffer to be plotted (BEAM, CCT, CLEAN, DIRTY, FIELDS, MASK, etc.. ), or any Sic Image variable, or a file name.

```
[DISPLAY\]VIEW ?
```

will list the names of recognized keywords. If Variable is not one of the recognized keywords, but an existing Image variable, this image will be displayed.

FirstPlane and LastPlane

are optional arguments to restrict the range of channels to be plotted (default: planes between variables FIRST and LAST). If only FirstPlane is specified, SHOW only that plane.

VIEW is also controlled by a set of variables, available in the View% global structure. VIEW shows 4 (or 6) panels, representing the Integrated area, the current channel, and the Integrated spectrum and the current spectrul (in possibly 2 different scales). An interactive control of the View is possible using the cursor, unless the /NOPAUSE option is given.

The spectral panels can display line identifications based on the current CATALOG. If a variable REDSHIFT exists, the frequency scale is corrected for the source Redshift, so that line identification remains possible.

#### 17.15.1 VIEW /NOPAUSE

```
[DISPLAY\]VIEW Argument [FirstPlane [LastPlane]] /NOPAUSE
```

Just display the panels as currently defined, without looping with the Graphic cursor for interactive view.

This will be the default mode if variable DO\_LOOP is set to NO.

**17.15.2 VIEW /OVERLAY**

```
[DISPLAY\]VIEW Argument [FirstPlane [LastPlane]] [/NOPAUSE]
/OVERLAY [Variable [Channel]]
```

Overlay (in contours) the specified Channel of the specified SIC 2 or 3-D Variable. The default Variable is CONTINUUM, the continuum image. If Variable is a 3-D SIC Variable, Channel indicates which plane is overlaid (default: last one).

**17.15.3 VIEW Keys**

Position-independent actions:

```
Press E key: EXIT loop
Press H key: HELP display
Press P key: PRINT plot in "ha" subdirectory
Press Q key: QUIT loop
Press X key: EXTRACT on disk current zoomed region
Press N key: Toggle Narrow - Wide mode
```

Cursor on images:

```
Left clic: Display spectrum at pointed position
Right clic: Define a polygon
Press B key: BACK to full field of view
Press C key: COORDINATES toggled from absolute to relative and back
Press M key: Display MASK if any
Press S key: SLICE definition (velocity-position)
Press U key: UNKILL pointed pixel
Press Z key: ZOOM defined spatial region
Press V key: Display map coordinates at current position
Press W key: WRITE Integrated Area image
```

Cursor on spectra:

```
Left clic in Selected Spectrum: Display selected velocity channel
Left clic in Integrated Spectrum: Define velocity range
Press B key: BACK to full velocity range
Press C key: COORDINATES toggled from freq/velo to channels and back
Press L key: LABEL spectral Lines
Press M key: MOVIE
Press Z key: ZOOM defined velocity region
Press W key: WRITE Integrated (and current) Spectrum
```

Cursor outside plots:

```
Press B key: BACK to full velocity range AND full field of view
```

Returned values are found in view%current structure. The ZOOM action produces a sub-cube named EXTRACTED. The SLICE action produces a 2-D data set named SLICED. As any other SIC Image variable, EXTRACTED and



SLICED can be written on disk using command WRITE.

#### 17.15.4 VIEW Scripts

The VIEW plot is done by procedure p\_view\_cct for Clean Components CCT and p\_view\_map for data cubes.

#### 17.15.5 VIEW Variables

VIEW uses the SHOW control variables SIZE, CENTER, RANGE and CROSS. In addition, it has its own control variables

view%expand	0.8	Character and Tick expansion factor
view%contour	NO	Contour the current channel map
view%movie	0	Elapsed time in seconds for a movie (0 means guess)
view%side	YES	Display values in side Window
view%status%rima	NO	Relative coordinates in Images
view%status%rspe	NO	Relative coordinates in Spectra

#### 17.15.6 VIEW Keywords:

VIEW recognizes the following keywords

BEAM	Synthesized beam(s)
CCT	Clean Cumulative Flux
CLEAN, DIRTY, SKY	Usual sky maps
NOISE	per channel noise
PRIMARY	Primary beams

or any other 3-D SIC variable.

VIEW falls back to SHOW for un-recognized keywords, such as MOMENTS COMPOSITE, UV, etc...

#### 17.15.7 BEAM

VIEW BEAM [PLANE|FIELD Kn]

View some sub-cube of the (up to 4-D) dirty Beam.

The 2nd argument indicates whether VIEW shows dirty beams of all Fields for a given frequency plane (PLANE keyword), or all Frequency-dependent beams for a given Field.

The 2nd and 3rd arguments are optional if the beam is only 2-D or 3-D,

which occurs for a single field or a frequency-independent beam in Mosaics (narrow band approximation).

### 17.15.8 PRIMARY

VIEW PRIMARY [PLANE|FIELD Kn]

View some sub-cube of the (up to 4-D) primary Beams.

The 2nd argument indicates whether VIEW shows all Fields for a given frequency plane (PLANE keyword), or all Frequency-dependent beams for a given Field.

The 2nd and 3rd arguments are optional if the beam is only 2-D or 3-D, which occurs for a single field or a frequency-independent beam in Mosaics (narrow band approximation).

## 18 CLEAN Language Internal Help

### 18.1 Language

CLEAN\ Language Summary

The CLEAN\ Language contains commands related to UV data handling, UV to DataCubes conversion and DataCube processing.

ALMA	: Joint deconvolution of ALMA and ACA dirty images
BUFFERS	: List and Display the known buffer status
CCT_CLEAN	: Compute CLEAN image from Clean Component Table, without resi
CCT_CONVERT	: Convert an image into a Clean Component Table
CCT_MERGE	: Merge two Clean Component Tables
CLEAN	: Deconvolve a dirty image using the current METHOD
DISCARD	: Discard one of the active data buffers
DUMP	: Dump the control parameters of the deconvolution algorithms
FIT	: Fit the dirty beam
MAP_COMBINE	: Combine two data Cubes
MAP_COMPRESS	: Average a Cube by several channels
MAP_INTEGRATE	: Compute a Moment 0 Map
MAP_REPROJECT	: Spatial resampling of a Cube
MAP_RESAMPLE	: Resample a Cube on a different Velocity/Frequency scale
MAP_SMOOTH	: Smooth by N channels

```

MOSAIC      : Toggle the mosaic mode
MX          : Iteratively image and deconvolve a dirty image
PRIMARY     : Apply primary beam correction
READ        : Read the input files in internal buffers
SPECIFY     : Change the Frequency / Velocity scale or the Telescope
SUPPORT     : Define the support used to search clean components
UV_BASELINE : Subtract a continuum baseline from a Line UV data
UV_CHECK    : Check UV data for null visibilities or per channel flags.
UV_COMPRESS : Compress a Line UV data into another Line UV data
UV_CONTINUUM : Compress a Line UV data into a Continuum UV data
UV_EXTRACT  : Extract a range from
UV_FILTER   : Filter out (line) channels
UV_FLAG     : Interactively flag UV data
UV_MAP      : Build the dirty image and beam from a UV table
UV_RESAMPLE : Resample (in Velocity) the UV data
UV_RESIDUAL : Subtract Clean Component from the UV Data
UV_RESTORE  : Restore a Clean image from UV data and Clean Components
UV_REWEIGHT : Evaluate UV weights from visibility statistics
UV_SHIFT    : Shift a UV table to common phase center
UV_SMOOTH   : Smooth spectrally a Line UV data
UV_SPLIT    : Split a UV table into Line and Continuum
UV_STAT     : Gives beam sizes and noise properties as a function of
              tapering or robust weighting parameter
UV_TIME     : Time average the current UV data
UV_TRIM     : Suppress useless information from UV data
UV_TRUNCATE : Truncate the baseline range of the UV data
WRITE       : Save internal buffers or Image variables onto output files

```

## 18.2 ALMA

```

[CLEAN\]ALMA [FirstPlane [LastPlane]] [/PLOT Clean|Residu] [/FLUX
Fmin Fmax] [/QUERY] [/NOISE] [/METHOD]

```

Joint deconvolution methods specific to ALMA+ACA observations.

The ALMA simulator can be accessed either by typing "@ alma" at the prompt or from the MAPPING main menu.

## 18.3 BUFFERS

```
[CLEAN\]BUFFERS
```

List the status (sizes) of known buffers. Active buffers can be nullified by using the DISCARD command.

### 18.3.1 BUFFERS AGAINS

AGAINS is a buffer containing the results of a self-calibration with command SELF CAL. It is a special table in the following format. Each line contains a different time stamp. Column 1 is the Time (in seconds), Col 2 the Date (in Days, with an arbitrary origin), Col 3 the number of antennas, Col 4 the antenna reference number, and then, for each antennas  $i$ , Cols  $(2+3*i:2+3*i)$  contains the Amplitude correction factor, the Phase correction (in degree), and the Signal-to-noise of the correction.

### 18.3.2 BUFFERS BEAM

BEAM is a 2,3 or 4-D image buffer containing the synthesized beam computed by UV\_MAP (or by READ BEAM).

### 18.3.3 BUFFERS CCT

CCT is a special 3-D array containing the Clean Component Table. The first dimension contains  $(x,y,f)$ , the flux (in Jy) at offset  $x,y$  (in radians). The second dimension handles the number of channels. The last dimension handles the Clean iteration number.

### 18.3.4 BUFFERS CGAINS

CGAINS is a pseudo-UV table containing the complex gain correction resulting from a SELF CAL command (or read by READ CGAINS). It is analogous to a single-channel UV table, but interpreted by IMAGER as gain corrections to apply to the UV data by command APPLY.

### 18.3.5 BUFFERS CLEAN

CLEAN is the deconvolved 2 or 3-D image produced by UV\_MAP (or read by READ CLEAN). It is not corrected for primary beam attenuation.

For Mosaics, command CLEAN produces a SKY brightness map, corrected from primary beam attenuations.

### 18.3.6 BUFFERS CLIPPED

CLIPPED is a 2-D table containing the Clipped spectra produced by command UV\_PREVIEW. Col 1 contains the Velocity, Cols 2:N+1 the spectra for the  $N$  tapers used in UV\_PREVIEW, Col  $N+2$  the natural weights.

### 18.3.7 BUFFERS CONTINUUM

CONTINUUM contains the pseudo-UV table used (and created) by command UV\_MAP /CONTINUUM to construct the continuum image. See command UV\_CONTINUUM for details.

### 18.3.8 BUFFERS DIRTY

DIRTY contains the dirty image produced by UV\_MAP. Its interpretation is different for a Single field than for a Mosaic.

### 18.3.9 BUFFERS EXTRACTED

EXTRACTED contains the 3-D data cube produced by command EXTRACT

### 18.3.10 BUFFERS FIELDS

FIELDS is an intermediate buffer created by SHOW PRIMARY. It is a transposed version of the PRIMARY buffer, in order (l,m,f) where f is the field number.

Note: there is a confusion with the FIELDS structure created by READ UV on Mosaic UV tables.

### 18.3.11 BUFFERS MASK

MASK contains the Mask computed by command MASK (or read by READ MASK). It may be used (or not) for CLEAN, depending on the selected type of Support (see SUPPORT /MASK and MASK USE commands).

### 18.3.12 BUFFERS M\_AREA

M\_AREA is a 2-D image containing the integrated area computed by command MOMENTS (CASA 0-th moment)

### 18.3.13 BUFFERS M\_PEAK

M\_PEAK is a 2-D image containing the peak flux computed by command MOMENTS (CASA 8-th moment)

### 18.3.14 BUFFERS M\_VELO

M\_VELO is a 2-D image containing the mean velocity computed by command MOMENTS. Its value depends on the method used in command MOMENTS: it can be the 1-st moment, or a fit of the peak velocity.

### 18.3.15 BUFFERS M\_WIDTH

M\_WIDTH is a 2-D image containing the velocity dispersion computed by command MOMENTS. It is equivalent to the Full Width at Half Maximum if the line shape is Gaussian.

### 18.3.16 BUFFERS PRIMARY

PRIMARY is the primary beam, computed by command PRIMARY or read by command READ PRIMARY. It may be 2-D (for single fields) or 3-D (for Mosaics). In the latter case, it is in the order (f,l,m) where f is the field number.

### 18.3.17 BUFFERS RESIDUAL

RESIDUAL is the image of the residuals from the Clean deconvolution.

### 18.3.18 BUFFERS SHORT

SHORT is the Short-Spacing image, computed by commands UV\_SHORT or XY\_SHORT, or read by command READ SINGLE.

### 18.3.19 BUFFERS SINGLE

SINGLE is the Single-Dish data read by command READ SINGLE. It may be a Class-table or a 3-D data cube.

### 18.3.20 BUFFERS SKY

SKY is a 3-D image buffer containing the current estimate of the Sky brightness distribution. It is provided by command PRIMARY from the CLEAN and PRIMARY buffers for single-field data, but by command CLEAN for Mosaics. Noise is not uniform in SKY image.

### 18.3.21 BUFFERS SLICED

SLICED is 2-D buffer produced by the SLICE command.

### 18.3.22 BUFFERS SPECTRUM

SPECTRUM is a 2-D table containing the spectra produced by command UV\_PREVIEW. Col 1 contains the Velocity, Cols 2:N+1 the spectra for the N tapers used in UV\_PREVIEW, Col N+2

### 18.3.23 BUFFERS UV

UV is the current UV data. It is initially set by command READ UV, but modified by many UV\_like commands (resampling, calibration, etc...)

### 18.3.24 BUFFERS UV\_FIT

UV\_FIT handles the results of the UV\_FIT command. It is a special format 2-D table. See HELP UV\_FIT for details.

### 18.3.25 BUFFERS UVCONT

UVCONT handles the intermediate (pseudo-)UV table created and used by command UV\_MAP /CONT for Multi-Frequency-Synthesis. It is a valid 2-D UV table, but which have more than 1 visibility for the same time and baseline pair, with different (frequency-scaled) (u,v) coordinates. Such UV tables can be properly imaged, but not properly self-calibrated.

### 18.3.26 BUFFERS UVRADIAL

UVRADIAL handles an azimuthally averaged version of the UV data. It is produced by command UV\_RADIAL.

### 18.3.27 BUFFERS WEIGHT

WEIGHT is the equivalent of PRIMARY for Mosaics. It is a 2 or 3-D image buffer containing the relative response given by all pointings of the Mosaic coverage.

## 18.4 CCT\_CLEAN

[CLEAN\]CCT\_CLEAN [Niter]

Convert the CCT Clean Component Table into the CLEAN image. The resid-

uals are not added at this stage, contrary to what is done by the CLEAN command.

Niter is the last iteration to be retained (to be implemented). If not present, all components are considered.

## 18.5 CCT\_CONVERT

[CLEAN\]CCT\_CONVERT [Threshold]

Convert the CLEAN image into the CCT Clean Component Table.

Threshold is the minimum (absolute value of) flux per pixel retained. Default is 0

## 18.6 CCT\_MERGE

[CLEAN\]CCT\_MERGE Out In1 In2

Combine two input Clean Component Tables.

Out can be a file name or an existing Image variable. The distinction is made by the existence of a "." in the name

If it is a file, it is created like the In1 Variable

If it is an Image variable, it must match the number of channels of the In1 Variable, and be large enough to handle the total number of components.

In1 and In2 can be file names or existing Image variables. They must match in terms of number of channels.

## 18.7 CLEAN

[CLEAN\]CLEAN [FirstPlane [LastPlane]] [/RESTART [File]] [/PLOT Clean|Residu]

[/FLUX Fmin Fmax] [/QUERY] [/NITER NiterList] [/ARES AresList]

Deconvolve a Mosaic or Single-field using the current METHOD (in SIC variable METHOD). See INPUT CLEAN for the other SIC variables controlling the deconvolution process. Supported methods are CLARK, HOGBOM, MRC, MULTISCALE and SDI. Use HELP CLEAN Method and/or HELP CLEAN METHOD-NAME for further details on each algorithm.

Clean the specified plane interval (default: planes between variables FIRST and LAST). If only FirstPlane is specified, Clean only that plane.



This command allows a per-plane definition of the convergence criteria CLEAN\_NITER and CLEAN\_ARES.

The user can control the algorithm through SIC variables. New values can be given using "LET VARIABLE value". For ease of use, and whenever it is possible, a sensible value of each parameter will automatically be computed from the context if the value of the corresponding variable is set to its default value, i.e. zero value and empty string. A few variables are initialized to "reasonable" values.

[CLEAN\]CLEAN ?

Will list all main CLEAN\_\* variables controlling the CLEAN parameters for the current METHOD.

HELP CLEAN Variables will give a more complete list.

### 18.7.1 CLEAN /FLUX

[CLEAN\]CLEAN [FirstPlane [LastPlane]] /FLUX Fmin Fmax [/PLOT Clean|Residu] [/QUERY] [/NITER NiterList] [/ARES AresList]

Display the cumulative Clean flux as Clean progresses. This option is inactive in Parallel mode.

### 18.7.2 CLEAN /PLOT

[CLEAN\]CLEAN [FirstPlane [LastPlane]] /PLOT Clean|Residu [/FLUX Fmin Fmax] [/QUERY] [/NITER NiterList] [/ARES AresList]

Display the iterated Clean or Residual image for Cleaning methods which have major cycles (CLARK or SDI). This option is inactive in Parallel mode.

### 18.7.3 CLEAN /QUERY

[CLEAN\]CLEAN [FirstPlane [LastPlane]] /PLOT Clean|Residu /QUERY [/FLUX Fmin Fmax] [/NITER NiterList] [/ARES AresList]

\*\*\* Obsolescent \*\*\*

Prompt for continuation when a Major cycle is complete. This option is inactive in Parallel mode.

As a replacement of this facility, we suggest you to fragment your CLEAN in several steps, using the /RESTART option and the VIEW CLEAN (or RESIDUAL) command after each step.

#### 18.7.4 CLEAN /NITER

```
[CLEAN\]CLEAN [FirstPlane [LastPlane]] /NITER NiterList [/PLOT
Clean|Residu] [/FLUX Fmin Fmax] [/QUERY] [/ARES AresList]
```

Use a per-plane value for the number of iterations, instead of the global NITER variable. NiterList should be a 1-D integer array of dimension the number of channels.

This option is only available through the CLEAN command, not through the specific command of each method.

#### 18.7.5 CLEAN /ARES

```
[CLEAN\]CLEAN [FirstPlane [LastPlane]] /ARES AresList [/PLOT
Clean|Residu] [/FLUX Fmin Fmax] [/QUERY] [/NITER NiterList]
```

Use a per-plane value for the absolute residual used to stop cleaning, instead of the global ARES variable. AresList should be a 1-D real array of dimension the number of channels.

#### 18.7.6 CLEAN /RESTART

```
[CLEAN\]CLEAN [FirstPlane [LastPlane]] /RESTART [File] [/PLOT
Clean|Residu]
[/FLUX Fmin Fmax] [/QUERY] [/NITER NiterList] [/ARES AresList]
```

Instruct CLEAN to start from the specified Clean Component Table stored in the specified File, or those currently in memory if no File is given.

This can be used to re-start a Clean that was not deep enough. It can be used to split the Clean operation in several steps, possibly changing the support at each step, or even the Clean METHOD.

For spectral data, the starting model should have the same number of channels, or have only 1. The later capability can be used to start from the Clean Components derived from a Continuum-only data set, so that deconvolution proceeds to find out the line-only structure. This is an alternative to separate deconvolution of Continuum and continuum-subtracted data followed by addition of the Clean images.

**18.7.7 CLEAN Methods:**

CLARK	A minor/major cycle cleaning using FFTs for speed Fast, but less stable than others.
HGOBOM	The basic deconvolution method, working component per component. Slow but robust
MRC	A dual-scale multi-resolution Clean working on a smooth and a difference map. Fast, but with no notions of Clean components
MULTISCALE	A 3-scales multi-resolution-Clean working on 3 smoothed versions of the map. Slow, but very stable and adapted to sources with extended structures.
SDI	A major-cycle only method. Good for extended structures but not very performant overall.

**18.7.8 CLARK**

```
CLEAN [FirstPlane [LastPlane]] [/PLOT Clean|Residu] [/FLUX Fmin
Fmax] [/QUERY]
```

```
with METHOD = CLARK
```

A Major-Minor cycles CLEAN method, originally developed by B.Clark, in which clean components are selected using a limited beam patch, and deconvolved through Fourier transform at each major cycle. In mosaic mode (See command MOSAIC), a mosaic clean is performed. Rings and/or stripes may appear on extended sources. Faster than the HGOBOM method for single fields but maybe slower for mosaics. The strategy to search for CLEAN components in CLARK method does not work properly when the secondary side lobes are too large (e.g. larger than 0.3), or in case of high phase noise.

**18.7.9 HGOBOM**

```
CLEAN [FirstPlane [LastPlane]] [/FLUX Fmin Fmax] [/RESTART [File]]
```

```
with METHOD = CLEAN
```

The simplest CLEAN algorithm, originally developed by Hogbom. In mosaic mode (See command MOSAIC), a mosaic clean is performed. Rings and or stripes may appear on extended sources. It is slower than CLARK for a single field but maybe faster for a mosaic. It is extremely robust. Cleaning can be interrupted by pressing C at any time.

**18.7.10 MRC**

```
CLEAN [FirstPlane [LastPlane]] [/PLOT Clean|Residu] [/FLUX Fmin
```

Fmax] [/QUERY]

with Method = MRC

Perform a Multi-Resolution CLEAN on the current dirty image. MRC does not support mosaics for theoretical reasons.

If option /PLOT is given, a display of the CLEAN or RESIDUAL map will be shown at each major cycle, depending on the argument (default: Residual). The user will be prompted for continuation when the /QUERY option is present. The cumulative, already cleaned flux is displayed in real time in an additional window while cleaning goes on when the /FLUX option is present. Parameters of the /FLUX option are then used to give the flux limits for this display. A summary plot with the Difference, Smooth, and total CLEANed maps is also displayed.

### 18.7.11 MULTI

CLEAN [FirstPlane [LastPlane]] [/FLUX Fmin Fmax] [/RESTART [File]]

with METHOD = MULTI

Perform a 3-scales Hogbom-like deconvolution. At each minor cycle, the scale with the highest signal to noise is used to define the Clean Components to retain. The algorithm is thus very stable.

The cumulative, already cleaned flux is displayed in real time in an additional window while cleaning goes on when the /FLUX option is present. Parameters of the /FLUX option are then used to give the flux limits for this display.

MULTI also works on mosaics. The smoothing ratio can be controlled by variable CLEAN\_SMOOTH.

### 18.7.12 SDI

CLEAN [FirstPlane [LastPlane]] [/PLOT Clean|Residu] [/FLUX Fmin Fmax] [/QUERY] [/RESTART [File]]

with METHOD = SDI

Perform a Steer-Dewdney-Ito CLEAN. This clean method selects an ensemble of clean components and remove them at once using FFTs. It works best for extended sources and UV coverages with short spacings. In such a case, it may avoid the "ringing" features which appear using the CLARK

or HOGBOM techniques. In mosaic mode (see command MOSAIC), a mosaic clean is performed.

SDI is very sensitive to the selected support (see MASK and SUPPORT commands), especially when the dirty beam sidelobes are significant.

### 18.7.13 Variables:

#### Basic CLEAN parameters

CLEAN_GAIN	[        ]	Loop gain
CLEAN_STOP	[        ]	Stopping criterium (string)
CLEAN_NITER	[        ]	Maximum number of clean components
CLEAN_FRES	[        %]	Maximum value of residual (Fraction of peak)
CLEAN_ARES	[Jy/Beam]	Maximum value of residual (Absolute)
CLEAN_POSITIVE	[        ]	Minimum number of positive components at start
CLEAN_NKEEP	[        ]	Min number of components before convergence

#### Clean beam user specification

BEAM_SIZE	[ 0 0 0 ]	Major, Minor (in arcsec) and PA (in Degree)
-----------	-----------	---

#### Method dependent CLEAN parameters

CLEAN_INFLATE	[        ]	Maximum Inflation factor for UV_RESTORE (MULTISCAL)
CLEAN_NCYCLE	[        ]	Max number of Major Cycles (SDI & CLARK methods)
CLEAN_NGOAL	[        ]	Max number of comp. in Cycles (ALMA method)
CLEAN_RATIO	[        ]	Smoothing factor (MRC default 0: guess, otherwise
CLEAN_SEARCH	[        ]	Threshold to search Clean Comp. in a Mosaic (def 0
CLEAN_SIDELOBE	[        ]	Min threshold to fit the synthesized beam
CLEAN_SMOOTH	[        ]	Smoothing ratio: MRC (def 2 or 4) and MULTISCALE
CLEAN_SPEEDY	[        ]	Speed-up factor (CLARK)
CLEAN_TRUNCATE	[        ]	Threshold for restoring a Mosaic (def 0.2)
CLEAN_WORRY	[        ]	Worry factor (CLARK and MULTISCALE)

#### Old (seldom used) names like in MAPPING

BLC	[ pixel]	Bottom left corner of cleaning box
TRC	[ pixel]	Top right corner of cleaning box
BEAM_PATCH	[ pixel]	Size of cleaning beam ** not clear **

#### Restoration control CLEAN parameters

CLEAN_RESIDUAL	[-1,0,1]	Control how residuals are added or not - For debu
----------------	----------	---

### 18.7.14 BEAM\_SIZE

BEAM\_SIZE is a Real array of size 3 containing the user-specified values for the Clean beam size, with BEAM\_SIZE[1] the Major axis, BEAM\_SIZE[2]

the Minor axis (both in arcsec) and BEAM\_SIZE[3] the Position angle (in degrees, North towards East).

If BEAM\_SIZE[1] and BEAM\_SIZE[2] are 0, the CLEAN or FIT commands will determine the Clean beam size (available in variable BEAM\_FITTED similar to BEAM\_SIZE) by adjusting the dirty beam main peak.

If only one of BEAM\_SIZE[1] and BEAM\_SIZE[2] is non zero, it will be used as the Clean beam size for a circular beam.

If both are non zero, BEAM\_SIZE totally specifies the Clean beam size. BEAM\_FITTED is thus set to the BEAM\_SIZE values when used.

### 18.7.15 CLEAN\_ARES

This is the minimal flux in the dirty map that the program will consider as significant. Alternatively, the threshold can be specified as a fraction of the peak flux using CLEAN\_FRES. Once this level has been reached the program stops subtracting, and starts the restoration phase. The unit for this parameter is the map unit (typically Jy/Beam). The parameter should usually be of the order of magnitude of the expected noise in the clean map.

If 0, CLEAN\_FRES will be used instead. If all of CLEAN\_NITER, CLEAN\_ARES and CLEAN\_FRES are 0, an absolute residual equal to the noise level will be used for CLEAN\_ARES.

Short form is ARES.

This may be overruled by the /ARES option which imposes a limit per plane through an array of values.

### 18.7.16 CLEAN\_FRES

This is the minimal fraction of the peak flux in the dirty map that the program will consider as significant. Alternatively, an absolute threshold can be specified using CLEAN\_ARES. Once this level has been reached the program stops subtracting, and starts the restoration phase. This parameter is normalized to 1 (neither in % nor in db). It should usually be of the order of magnitude of the inverse of the expected dynamic range of the intensity.

If 0, CLEAN\_ARES will be used instead. If all of CLEAN\_NITER, CLEAN\_ARES and CLEAN\_FRES are 0, an absolute residual equal to the noise level will

be used for CLEAN\_ARES.

Short form is FRES.

#### 18.7.17 CLEAN\_GAIN

This is the gain of the subtraction loop. It should typically be chosen in the range 0.05 and 0.3. Higher values give faster convergence, while lower values give a better restitution of the extended structure. A sensible default is 0.2.

Short form is GAIN.

#### 18.7.18 CLEAN\_INFLATE

Maximum Inflation factor for UV\_RESTORE (MULTISCALE method). If the number of true (i.e. pixel based) Clean components found by MULTISCALE is larger than CLEAN\_INFLATE times the number of compressed (i.e. those with the smoothing factor information) components, expansion of the compressed components will not be possible, and UV\_RESTORE or CLEAN/RESTART will not be useable.

The default is 121, large enough to handles all expansion, but it might exceed the available memory. Smaller values are often acceptable. Better solutions might be found in the future, and this parameter suppressed. Apart from memory usage, this number has no consequence on the algorithm.

#### 18.7.19 CLEAN\_NCYCLE

Maximum number of Major Cycles for the SDI and CLARK methods.

#### 18.7.20 CLEAN\_NGOAL

Number of clean components to be selected in a Cycle in the ALMA heterogeneous array cleaning method.

#### 18.7.21 CLEAN\_NITER

This is the maximum number of components the program will accept to subtract. Once it has been reached, the program starts the restoration phase.

If 0, the program will guess a number, based on the image size and maximum signal-to-noise ratio, and specified residual level CLEAN\_ARES and/or CLEAN\_FRES.

Short form is NITER.

This may be overruled by the /NITER option which imposes a limit per plane through an array of values.

#### 18.7.22 CLEAN\_NKEEP

This is an integer specifying the minimum number of Clean components before testing if Cleaning has converged. The convergence criterion is a comparison of the cumulative flux evolution separated by CLEAN\_NKEEP components. If th

IF CLEAN\_NKEEP is 0, CLEAN will ignore this convergence criterion, and continue clean until the CLEAN\_NITER, CLEAN\_ARES or CLEAN\_FRES criteria indicate to stop.

With CLEAN\_NKEEP > 0, CLEAN will explore the stability of the total clean flux over the last CLEAN\_NKEEP iterations. For a positive (resp. negative) source, if the Clean flux becomes smaller (resp. larger) than the Clean flux CLEAN\_NKEEP iterations earlier, CLEAN will stop.

Using CLEAN\_NKEEP about 70 is a reasonable value. Some special cases (faint extended sources) may require larger values of CLEAN\_NKEEP.

#### 18.7.23 CLEAN\_POSITIVE

The minimum number of positive components before negative ones are selected.

#### 18.7.24 CLEAN\_RESIDUAL

An integer code indicating what the Clean image will contain. Its usage is reserved for tests or specific algorithm using the basic CLEAN as an engine.



- 1 The CLEAN image contains only the Clean components, not convolved with the Clean beam.
- 0 Normal behaviour: Convolve Clean components with Clean beam and add the residuals.
- 1 Convolve Clean components, but do not add the residuals.

#### 18.7.25 CLEAN\_SEARCH

Fraction of peak response of the primary beams coverage beyond which no Clean component is searched in a Mosaic deconvolution.

The default is 0.2.

#### 18.7.26 CLEAN\_SIDELOBE

Minimal relative intensity to consider for fitting the synthesized beam to obtain the Clean beam parameters (BEAM\_FITTED variable) when 0. The default is 0.35.

In case of poor UV coverage, CLEAN\_SIDELOBE should be higher than the maximum sidelobe level to perform a good Gaussian fit. Some particularly bad UV coverage may not allow any good fit at all, however.

#### 18.7.27 CLEAN\_SMOOTH

Smoothing factor between different scales in the MRC and MULTISCALE methods. The default is 2 or 4 for MRC depending on image size. It is  $\sqrt{3}$  for MULTISCALE and may be set to larger values if needed.

#### 18.7.28 CLEAN\_SPEEDY

Speed-up factor for the CLARK major cycles. The default is 1.0. Larger values may be used, but at the expense of possible instabilities of the algorithm.

#### 18.7.29 CLEAN\_STOP

CLEAN\_STOP is a 2-elements character string that defines the Clean

stopping criterium.

If CLEAN\_STOP is not empty, it supersedes the older CLEAN\_ARES, CLEAN\_FRES and CLEAN\_NITER variables (and their even older ARES, FRES, NITER historical equivalent), and even the CLEAN\_NKEEP variable, providing a more flexible syntax to specify the stopping criterium.

The general syntax is

```
LET CLEAN_STOP Value [Unit]
```

```
LET CLEAN_STOP 1 Sigma      Indicates stopping at 1 times the noise level
```

```
LET CLEAN_STOP 10 mJy       Indicates stopping at 0.01 Jy/beam
```

```
LET CLEAN_STOP 1 %          Indicates stopping at 0.01 of the peak value
```

```
LET CLEAN_STOP 100 Iterations Set the max number of iterations to 100
```

```
LET CLEAN_STOP 20 Stop      Indicates convergence is tested over 20 itera
```

If no unit is specified, the last specified unit is used instead. Sub-units (mJy, Jy, milliJy, microJy, etc...) are allowed for convenience.

CLEAN\_STOP overwrites the previously specified CLEAN\_ARES, CLEAN\_FRES, CLEAN\_NITER and CLEAN\_NKEEP values when (and only when) CLEAN is executed.

## 2 CLEAN\_TRUNCATE

Fraction of peak response of the primary beams coverage under which the Sky brightness image is blanked in a Mosaic deconvolution.

It is also used as a default truncation value in the PRIMARY command.

The default is 0.2.

### 18.7.30 CLEAN\_WORRY

Worry factor in the MULTISCALE method for convergence. It propagates the S/N from one iteration to the other, so that if this S/N degrades, the method stops. Default is 0 (no propagation, and hence no test on S/N). The value should be < 1.0 in all cases.

### 18.7.31 METHOD

Method used for the deconvolution. Can be HGOBOM, MULTI, MRC, SDI or CLARK.

### 18.7.32 Old\_Names:

Some of the CLEAN parameters have kept their old names: BLC, TRC and BEAM\_PATCH (which are seldom used)

Others have equivalent short names: ARES, FRES, GAIN, NITER for which the CLEAN\_ prefix may be omitted.

MAJOR, MINOR, ANGLE (which were used to control the Clean beam size) have been replaced by BEAM\_SIZE[3]

### 18.7.33 BLC

These are the (pixel) coordinates of the Bottom Left Corner of the cleaning box. The default (0,0) means the bottom left quarter ( $N_x/4, N_y/4$ ). If a SUPPORT is defined, BLC is ignored.

### 18.7.34 TRC

These are the (pixel) coordinates of the Top Right Corner of the cleaning box. The default (0,0) means the top right quarter ( $3*N_x/4, 3*N_y/4$ ). If a SUPPORT is defined, TRC is ignored.

### 18.7.35 MAJOR

This was the major axis (FWHP) of the Gaussian restoring beam. Replaced by BEAM\_SIZE[1] instead.

### 18.7.36 MINOR

This was the minor axis (FWHP) of the Gaussian restoring beam. Replaced by BEAM\_SIZE[2] instead.

### 18.7.37 ANGLE

This was the position angle (from North towards East, i.e. anticlockwise) of the major axis of the Gaussian restoring beam. Replaced by

BEAM\_SIZE[3] instead.

### 18.7.38 BEAM\_PATCH

The dirty beam patch to be used for the minor cycles in CLARK and MRC method. It should be large enough to avoid doing too many major cycles, but has practically no influence on the result. This size should be specified in pixel units. Reasonable values are between  $N/8$  and  $N/4$ , where  $N$  is the number of map pixels in the same dimension. If set to  $N$ , the CLARK algorithm becomes identical to the HOGBOM algorithm.

## 18.8 DISCARD

[CLEAN\]DISCARD BufferName

Discard (i.e. remove from the memory and the list of known variables) the specified buffer.

Only the most important buffers (e.g. DIRTY, CLEAN, etc...) can be discarded. The current list is:

CCT, CLEAN, CONTINUUM, DIRTY, MASK, PRIMARY, RESIDUAL,  
SINGLEDISH, SKY, UVCONT, UVSELF, UV\_MODEL

## 18.9 DUMP

[CLEAN\]DUMP [U]

Dump on screen the control parameters of the different CLEAN deconvolution algorithms, mainly for debugging purpose. "DUMP U" dumps the parameters as input by the user while "DUMP" dumps the parameters really used and/or modified by the deconvolution algorithm.

## 18.10 FIT

[CLEAN\]FIT [Plane] | [CHANNEL First Last] [FIELD First Last]  
[/THRESHOLD Value] [/JVM\_FACTOR [NoCircle]]

Fit the dirty beam to obtain the clean beam parameters.

For single fields, "FIT Plane" can be used to fit just one of the possible Frequency dependent beam planes. Note that the number of beam plane

can be different from that of image channels.

For mosaics, dirty beams can be up to 4-D, depending on Frequency and Field number. Keywords CHANNEL (or equivalently PLANE) and FIELD allow to restrict the fit to the specified range of Channels or Field numbers. All ranges are considered

Note that an automatic FIT is performed by all CLEAN algorithms when needed. The appropriate Frequency plane corresponding to each image channel is used. For mosaics, CLEAN takes the average of the fitted beam parameters on all fields.

User specified values can be used instead (see HELP FIT FixedValues).

### 18.10.1 FIT FixedValues

Clean beam parameters can also be specified by the users, by loading the BEAM\_SIZE array with values other than its default values (0,0,0). In this case, no automatic fit will be performed.

In general, we discourage this usage, as it may result in a very improper flux scaling if the beam size is inappropriate. This mode should be reserved to special cases where the beam cannot be properly fitted, or to have a circular beam by taking as beam size the geometrical mean of the fitted major and minor sizes.

Fixing the beam size should be associated to the FIT /JVM command to minimize (but not suppress !...) errors in total flux scaling.

### 18.10.2 FIT Results

Beam parameters are returned in the BEAM\_FITTED array which is analogous to the BEAM\_SIZE one (Major axis, Minor axis in arcsec, and Position angle, in degrees East from North), and in the BEAM\_JVM variable, that contains the scaling factor of the residuals.

### 18.10.3 FIT /JVM\_FACTOR

```
[CLEAN\]FIT [Plane] | [CHANNEL First Last] [FIELD First Last]
[/THRESHOLD Value] /JVM_FACTOR [NoCircle]
```

This option instructs the FIT command to estimate the so-called JvM factor (from Jorsater van Moorsel 1995), which is the ratio of Clean beam

area to Dirty beam area. The value is returned into the BEAM\_JVM variable.

The Dirty beam area is an ill-defined quantity (if no Zero spacing is included, the Dirty beam area tends toward Zero when a sufficiently large area is included). It is defined here by integrating only up to the first null of the Dirty beam.

In case of Dirty beams presenting shoulders around the main beam, this ratio may be used to adjust the contribution of residuals to the CLEAN image so that the flux is better preserved. For well-behaved beams, it should be quite close to 1.

NoCircle is an argument which, if present, indicates that the Clean and Dirty beam should not be circularized to derive the factor; this should be reserved for debugging.

#### 18.10.4 FIT /THRESHOLD

[CLEAN\]FIT /THRESHOLD Value [/JVM\_FACTOR]

Use Value instead of CLEAN\_SIDELOBE to fit only regions of the beam above Value by a Gaussian. Gaussian fit may give different sizes for significantly non-Gaussian beams.

#### 18.10.5 FIT BEAM\_SIZE

BEAM\_SIZE is a Real array of size 3 containing the user-specified values for the Clean beam size, with BEAM\_SIZE[1] the Major axis, BEAM\_SIZE[2] the Minor axis (both in arcsec) and BEAM\_SIZE[3] the Position angle (in degrees, North towards East).

If BEAM\_SIZE[1] and BEAM\_SIZE[2] are 0, the CLEAN or FIT commands will determine the Clean beam size (available in variable BEAM\_FITTED similar to BEAM\_SIZE) by adjusting the dirty beam main peak.

If only one of BEAM\_SIZE[1] and BEAM\_SIZE[2] is non zero, it will be used as the Clean beam size for a circular beam.

If both are non zero, BEAM\_SIZE totally specifies the Clean beam size. BEAM\_FITTED is thus set to the BEAM\_SIZE values when used.

### 18.10.6 FIT CLEAN\_SIDELOBE

Minimal relative intensity to consider for fitting the synthesized beam to obtain the Clean beam parameters (BEAM\_SIZE variable) when 0. The default is 0.30.

In case of poor UV coverage, CLEAN\_SIDELOBE should be higher than the maximum sidelobe level to perform a good Gaussian fit. Some particularly bad UV coverage may not allow any good fit at all, however.

## 18.11 MAP\_COMBINE

```
[CLEAN\]MAP_COMBINE OutCube CODE In1 In2 [Off] [/FACTOR A1 A2]
[/THRESHOLD T1 T2] [/BLANKING Bval]
```

Combine in different ways two input images (or data cubes)...

```
MAP_COMBINE also supports an "intuitive" , more mathematical syntax,
MAP_COMBINE OutCube = [A1*]In1 Oper [A2*]In2 [Off]
[/THRESHOLD T1 T2] [/BLANKING Bval]
```

where Oper can be any of the values allowed for CODE, or one of the 4 standard operators, +/\*, and scale factors are given in a natural way.

OutCube can be a file name or an existing SIC Image variable. The distinction is made by the existence of a "." in the name. If it is a file, it is created like the In1 Variable. If it is a SIC Image variable, it must exist and match the shape of In1.

In1 can be a file name or an existing SIC Image variable.

In2 can be a file name or an existing Image variable. The rank of In2 must be smaller than or equal to that of In1, and other dimensions must match.

CODE is the Operation Code: see HELP MAP\_COMBINE CODE for details. Off is an optional offset for the operation.

A1 and A2 are scale factors applied to In1 and In2 if needed (default 1).

T1 and T2 are thresholds below which no result is computed (default none).

**18.11.1 MAP\_COMBINE CODE**

```
[CLEAN\]MAP_COMBINE OutCube CODE In1 In2 [Off] [/FACTOR A1 A2]
[/THRESHOLD T1 T2] [/BLANKING Bval]
```

CODE is the operation code. Allowed values are

```
ADD      or PLUS      OutCube = A1*In1 + A2*In2 + Off
SUBTRACT or MINUS     OutCube = A1*In1 - A2*In2 + Off
DIVIDE   or OVER      OutCube = A1*In1 / A2*In2 + Off
MULTIPLY or TIMES     OutCube = A1*In1 * A2*In2 + Off
OPACITY                      OutCube = -Log( A1*In1 / A2*In2 + Off)
INDEX                      OutCube = Log( A1*In1 / A2*In2) / Log(Nu1/Nu2)
where Nu1 is the Frequency of In1, and Nu2 that of In2. Off is 0 if not
specified.
```

With the "intuitive" mathematical syntax,

```
MAP_COMBINE OutCube = [A1*]In1 Oper [A2*]In2 [Off]
```

Oper can be any of the above values for CODE, or one of the 4 standard operators, +, -, \*, /, and scale factors are given in a natural way, defaulting to 1 if not present.

**18.11.2 MAP\_COMBINE /BLANKING**

```
[CLEAN\]MAP_COMBINE OutCube CODE In1 In2 [/FACTOR A1 A2]
[/THRESHOLD T1 T2] /BLANKING Bval
```

Specify the Blanking value to be used in the OutCube. If not specified, the Blanking from In1 is used instead, and that of In2 if In1 has no Blanking.

**18.11.3 MAP\_COMBINE /FACTOR**

```
[CLEAN\]MAP_COMBINE OutCube CODE In1 In2 /FACTOR A1 A2
[/THRESHOLD T1 T2] [/BLANKING Bval]
```

Specify the factors to apply to In1 and In2. Default is 1.0. This option is not available in the "intuitive" math syntax, where the factors are specified directly.

**18.11.4 MAP\_COMBINE /THRESHOLD**

```
[CLEAN\]MAP_COMBINE OutCube CODE In1 In2 [/FACTOR A1 A2]
/THRESHOLD T1 T2] [/BLANKING Bval]
```

Specify the thresholds above which the computation is valid for In1 and



In2. For pixels below this threshold, the OutCube is blanked.

Default is no threshold (-huge(0.)).

## 18.12 MAP\_COMPRESS

[CLEAN\]MAP\_COMPRESS WhichOne Nc [First TYPE] [Output]

Resample (in frequency/velocity) a data cube by averaging NC adjacent channels.

WhichOne indicates which data cube must be compressed. Allowed values are

- DIRTY, CLEAN or SKY
- \*, which means all of the previous existing ones
- Any SIC Image Variable that is not a built-in buffer in IMAGER
- An existing GILDAS data file

MAP\_INTEGRATE only works on 3-D data cubes, replacing them by 2-D images.

Output is a string indicating where the results will be placed.

### 18.12.1 MAP\_COMPRESS Output

[CLEAN\]MAP\_COMPRESS WhichOne Nc [First TYPE] [Output]

Output is a string indicating where the results will be placed. It can be

- Any SIC Image Variable that is not a built-in buffer in IMAGER  
The variable must exist and be of adequate size.
- A file name. The command will write the result as a GILDAS data file with this name.

The distinction between SIC Image Variable and Filenames is based on the presence of a dot (".") or semi-colon (":") that indicate that the string refers to a filename.

Output is compulsory unless WhichOne refers to one of the allowed built-in buffer names (DIRTY, CLEAN or SKY) and forbidden if WhichOne is \*. When Output is not present, the result are written in place on the specified buffers.

## 18.13 MAP\_INTEGRATE

[CLEAN\]MAP\_INTEGRATE WhichOne Min Max Type [Output]

Compute the integrated intensity map(s) over the specified range from the specified data cube. Type can be VELOCITY FREQUENCY or CHANNELS.

WhichOne indicates which data cube must be compressed. Allowed values are

- DIRTY, CLEAN or SKY
- \*, which means all of the previous existing ones
- Any SIC Image Variable that is not a built-in buffer in IMAGER
- An existing GILDAS data file

MAP\_INTEGRATE only works on 3-D data cubes, replacing them by 2-D images.

Output is a name that indicates where the results will be placed,

### 18.13.1 MAP\_INTEGRATE Output

```
[CLEAN\]MAP_INTEGRATE WhichOne Min Max Type [Output]
```

Output is a string indicating where the results will be placed. It can be

- Any SIC Image Variable that is not a built-in buffer in IMAGER  
The variable must exist and be of adequate size.
- A file name. The command will write the result as a GILDAS data file with this name.

The distinction between SIC Image Variable and Filenames is based on the presence of a dot (".") or semi-colon (":") that indicate that the string refers to a filename.

Output is compulsory unless WhichOne refers to one of the allowed built-in buffer names (DIRTY, CLEAN or SKY) and forbidden if WhichOne is \*. When Output is not present, the result are written in place on the specified buffers.

### 18.14 MAP\_REPROJECT

```
[CLEAN\]MAP_REPROJECT Output Input
[/BLANKING Bval Eval]    [/LIKE Template]
[/PROJECTION Type Cx Cy [Angle]]
[/SYSTEM Type [Equinox]]
[/X_AXIS Nx Ref Val Inc]
[/Y_AXIS Ny Ref Val Inc]
```

Resample spatially a Map or Cube according to the specified projection (and coordinate system). The characteristics of the Output Cube can be controlled by the /LIKE option, or explicitly by a combination of /PRO-

JECTION, /SYSTEM, /X\_AXIS, /Y\_AXIS options.

Input can be a GILDAS data file, or a SIC image variable. Output is a GILDAS data file that is created by the command.

#### 18.14.1 MAP\_REPROJECT /BLANKING

```
[CLEAN\]MAP_REPROJECT Output Input
/BLANKING Bval Eval    [/LIKE Template]
[/PROJECTION Type Cx Cy [Angle]]
[/SYSTEM Type [Equinox]]
[/X_AXIS Nx Ref Val Inc]
[/Y_AXIS Ny Ref Val Inc]
```

Specify the desired Blanking value. If not present, this is inherited from the Input, or the Template if specified.

#### 18.14.2 MAP\_REPROJECT /LIKE

```
[CLEAN\]MAP_REPROJECT Output Input
/LIKE Template [/BLANKING Bval Eval]
```

Specify the shape and projection of the desired Output Cube from a Template. Template is either a GILDAS data file, or a SIC Header (or Image) variable.

The Blanking value, if not specified through /BLANKING, will be inherited from the Template.

The /LIKE option is incompatible with the /PROJECTION, /SYSTEM, /X\_AXIS and /Y\_AXIS options.

#### 18.14.3 MAP\_REPROJECT /PROJECTION

```
[CLEAN\]MAP_REPROJECT Output Input
[/BLANKING Bval Eval]
/PROJECTION Type Cx Cy [Angle]
[/SYSTEM Type [Equinox]]
[/X_AXIS Nx Ref Val Inc]
[/Y_AXIS Ny Ref Val Inc]
```

Specify the desired Projection center. If Angle is not specified, it is set to 0. Any argument with a value of \* is left unchanged from the Input Cube value.

This option is incompatible with the /LIKE option.

#### 18.14.4 MAP\_REPROJECT /SYSTEM

```
[CLEAN\]MAP_REPROJECT Output Input
[/BLANKING Bval Eval]
[/PROJECTION Type Cx Cy [Angle]]
/SYSTEM Type [Equinox]
[/X_AXIS Nx Ref Val Inc]
[/Y_AXIS Ny Ref Val Inc]
```

Specify the desired coordinate System. Equinox default to 2000.0 for EQUATORIAL system if not specified.

This option is incompatible with the /LIKE option.

#### 18.14.5 MAP\_REPROJECT /X\_AXIS

```
[CLEAN\]MAP_REPROJECT Output Input
[/BLANKING Bval Eval]
[/PROJECTION Type Cx Cy [Angle]]
[/SYSTEM Type [Equinox]]
/X_AXIS Nx Ref Val Inc
[/Y_AXIS Ny Ref Val Inc]
```

Specify the desired X axis sampling. Any argument with a value of \* is left unchanged from the Input Cube value.

This option is incompatible with the /LIKE option.

#### 18.14.6 MAP\_REPROJECT /Y\_AXIS

```
[CLEAN\]MAP_REPROJECT Output Input
[/BLANKING Bval Eval]
[/PROJECTION Type Cx Cy [Angle]]
[/SYSTEM Type [Equinox]]
[/X_AXIS Nx Ref Val Inc]
/Y_AXIS Ny Ref Val Inc]
```

Specify the desired Y axis sampling. Any argument with a value of \* is left unchanged from the Input Cube value.

This option is incompatible with the /LIKE option.

### 18.15 MAP\_RESAMPLE

[CLEAN\]MAP\_RESAMPLE WhichOne [Nc Ref Val Inc] [Result] [/LIKE Mold]

Resample 3-D data cubes on a different velocity scale.

Nc new number of channels  
 Ref New reference pixel  
 Val New velocity at reference pixel  
 Inc Velocity increment

WhichOne indicates which data cube must be compressed. Allowed values are

- Built-in buffers DIRTY, CLEAN, SKY, SINGLE or \*, which means all of the previous existing ones. Resampling is done in place.
- Any SIC Image Variable that is not a built-in buffer in IMAGER.
- A GILDAS data file

For the two later cases, the Result argument indicates where the resampled data cube is stored. Result can be a file name or an existing SIC variable of adequate dimensions.

MAP\_RESAMPLE only works on 3-D data cubes.

#### 18.15.1 MAP\_RESAMPLE /LIKE

[CLEAN\]MAP\_RESAMPLE WhichOne [Result] [/LIKE Mold]

Resample 3-D data cubes on the same velocity scale than the specified Mold. Mold can be a SIC variable or GILDAS data file.

### 18.16 MAP\_SMOOTH

[CLEAN\]MAP\_SMOOTH WhichOne Nc [Result] [/ASYMMETRIC]

Smooth a 3-D data cubes by Nc channels along the velocity axis.

Nc number of channels to be averaged in smoothing.

WhichOne indicates which data cube must be compressed. Allowed values are

- Built-in buffers DIRTY, CLEAN, SKY, SINGLE or \*, which means all of the previous existing ones. Smoothing is done in place.
- Any SIC Image Variable that is not a built-in buffer in IMAGER.
- A GILDAS data file

For the two later cases, the Result argument indicates where the smoothed data cube is stored. Result can be a file name or an existing SIC variable of adequate dimensions.

By default, the smoothing does not modify the spectral sampling of the cubes. While this naturally occurs when the smoothing number Nc is odd, the Nc even case requires a specific handling. For Nc even, the

smoothed channel at channel "i" sums up half of channel  $i - N_c/2$ , half of channels  $i + N_c/2$  and all channels in between. Thus for  $N_c=2$ , this is a Hanning smoothing.

Like for UV\_SMOOTH, this behaviour can be modified by option /ASYMMETRIC.

### 18.16.1 MAP\_SMOOTH /ASYMMETRIC

[CLEAN\]MAP\_SMOOTH WhichOne Nc [Result] /ASYMMETRIC

Make no attempt to preserve the spectral sampling when Nc is even: the reference channel is then shifted by half the channel spacing.

For odd Nc, the smoothing is naturally symmetric, so the option has no impact.

## 18.17 SPECIFY

[CLEAN\]SPECIFY Keyword [Values...] [/FOR SicVariable]

Specify or modify some information in internal buffers or in a Sic Image Variable.

Recognized values for Keyword are BLANKING, FREQUENCY, LINENAME, VELOCITY, TELESCOPE

If present the /FOR option indicates which buffer or Image variable should be affected. If no /FOR option is given, all relevant available buffers are affected (CLEAN, DIRTY, UV, etc...)

### 18.17.1 SPECIFY BLANKING

SPECIFY BLANKING Value /FOR SicVariable

Specify or Modify the blanking value in the specified Image variable SicVariable. Option /FOR is mandatory for this action.

### 18.17.2 SPECIFY FREQUENCY

SPECIFY FREQUENCY Value

Modify the rest frequency and recompute the velocity scale accordingly. Value is the new rest frequency in MHz

### 18.17.3 SPECIFY LINENAME

SPECIFY LINENAME Name

Change the spectral line name.

### 18.17.4 SPECIFY VELOCITY

SPECIFY VELOCITY Value

Modify the source velocity and recompute the rest frequency scale accordingly. Value is the new velocity in km/s.

### 18.17.5 SPECIFY TELESCOPE

SPECIFY TELESCOPE Name

Add or Replace the telescope section with the parameters (name, size, position) for the specified telescope name, essentially to get the most appropriate beam parameter.

A Telescope section is required for MOSAIC. The beamsize will depend on telescope diameter and frequency, with a telescope dependent factor. The default beam size is 1.13  $\Lambda/D$ .

## 18.18 MOSAIC

[CLEAN\]MOSAIC On|Off

Turn on or off the mosaic mode for deconvolution. Note that a READ PRIMARY command, or a UV\_MAP command working on a Mosaic UV Table, automatically switches on the mosaic mode. The program prompt changes to inform the user of the current operating mode for deconvolution.

## 18.19 MX

[CLEAN\]MX [FirstPlane [LastPlane]] [/PLOT Clean|Residu] [/FLUX Fmin Fmax] [/QUERY]

Make and deconvolve maps starting from a UV table. It combines UV\_MAP and CLEAN in a single step.

The mapping process is identical to UV\_MAP. It makes a map from UV data by gridding the UV data using a convolving function, and then Fast Fourier Transforming the individual channels. However, MX always produces a

single beam for all channels, thus neglecting frequency change between channels. MX enables to shift the map center and rotate the image, by shifting the phase tracking center and rotating the UV coordinates of the input UV table.

The CLEAN algorithm is similar to the CLARK method, but with major cycles operating directly on the ungridded UV table rather than in the image plane. Accordingly, aliasing affects only of the residuals, not the clean components. It is thus more accurate but also slower than CLARK as it asks for the gridding step at each major cycle. MX also shares the same limitation as CLARK on large sidelobes.

The user can control the algorithm through SIC variables. New values can be given using "LET VARIABLE value". For ease of use, and whenever it is possible, a sensible value of each parameter will automatically be computed from the context if the value of the corresponding variable is set to its default value, i.e. zero value and empty string. A few variables are initialized to "reasonable" values.

[CLEAN\]CLEAN ?

Will list all main CLEAN\_\* variables controlling the CLEAN parameters for the current METHOD.

HELP CLEAN Variables will give a more complete list.

[CLEAN\MX ?

Will list all MAP\_\* and CLEAN\_\* variables controlling the MX parameters.

### 18.19.1 MX Variables:

The list of control variables is (by alphabetic order, with the corresponding old names used by Mapping on the right)

New names	[ unit]	-- Description --	% Old Name
BEAM_STEP	[ ]	Channels per dirty beam	% MAP_BEAM_STEP
MAP_CELL	[ arcsec]	Image pixel size	
MAP_CENTER	[ string]	RA, Dec of map center, and Position Angle	
MAP_CONVOLUTION	[ ]	Convolution function	% CONVOLUTION
MAP_FIELD	[ arcsec]	Map field of view	
MAP_POWER	[ ]	Maximum exponent of 3 and 5 allowed in MAP_SIZE	
MAP_PRECIS	[ ]	Fraction of pixel tolerance on beam matching	
MAP_ROBUST	[ ]	Robustness factor	% UV_CELL[2]
MAP_ROUNDING	[ ]	Precision of MAP_SIZE	
MAP_SIZE	[ ]	Number of pixels	
MAP_TAPEREXPO	[ ]	Taper exponent	% TAPER_EXPO



```

MAP_TRUNCATE    [      %]  Mosaic truncation level
MAP_UVCELL      [      m]  UV cell size           % UV_CELL[1]
MAP_UVTAPER     [m,m,deg]  Gaussian taper         % UV_TAPER
MAP_VERSION     [      ]  Code version (0 new, -1 old)

```

#### Basic CLEAN parameters

```

CLEAN_GAIN      [      ]  Loop gain
CLEAN_STOP      [      ]  Stopping criterium (string)
CLEAN_NITER     [      ]  Maximum number of clean components
CLEAN_FRES      [      %]  Maximum value of residual (Fraction of peak)
CLEAN_ARES      [Jy/Beam] Maximum value of residual (Absolute)
CLEAN_POSITIVE  [      ]  Minimum number of positive components at start
CLEAN_NKEEP     [      ]  Min number of components before convergence

```

#### Clean beam user specification

```

BEAM_SIZE       [ 0 0 0 ] Major, Minor (in arcsec) and PA (in Degree)

```

#### Method dependent CLEAN parameters

```

CLEAN_INFLATE   [      ]  Maximum Inflation factor for UV_RESTORE (MULTISCAL
CLEAN_NCYCLE    [      ]  Max number of Major Cycles (SDI & CLARK methods)
CLEAN_NGOAL     [      ]  Max number of comp. in Cycles (ALMA method)
CLEAN_RATIO     [      ]  Smoothing factor (MRC default 0: guess, otherwise
CLEAN_SEARCH    [      ]  Threshold to search Clean Comp. in a Mosaic (def 0
CLEAN_SIDELOBE  [      ]  Min threshold to fit the synthesized beam
CLEAN_SMOOTH    [      ]  Smoothing ratio: MRC (def 2 or 4) and MULTISCALE
CLEAN_SPEEDY    [      ]  Speed-up factor (CLARK)
CLEAN_TRUNCATE  [      ]  Threshold for restoring a Mosaic (def 0.2)
CLEAN_WORRY     [      ]  Worry factor (CLARK and MULTISCALE)

```

#### Old (seldom used) names like in MAPPING

```

BLC             [ pixel] Bottom left corner of cleaning box
TRC             [ pixel] Top right corner of cleaning box
BEAM_PATCH      [ pixel] Size of cleaning beam ** not clear **

```

#### Restoration control CLEAN parameters

```

CLEAN_RESIDUAL  [-1,0,1] Control how residuals are added or not - For debu

```

## 18.20 PRIMARY

```
[CLEAN\]PRIMARY [BeamSize] [/TRUNCATE Percent]
```

Apply approximate primary beam correction to a single field deconvolved (CLEAN) image, in order to create the sky brightness image (named SKY). The truncation level is given by default by variable CLEAN\_TRUNCATE, and can be overridden by the /TRUNCATE option.

The primary beam model is a simple Gaussian. If BeamSize (in radian) is specified, uses the corresponding half-power beam size to determine the Gaussian beam. If not, the parameters are taken from the telescope parameters, as found in the telescope section of the CLEAN image and the observing frequency from the CLEAN image (e.g. for ALMA it uses  $1.13 \lambda/D$ ).

The SKY image is written with extension .lmv-sky by command WRITE.

### 18.20.1 PRIMARY /TRUNCATE

[CLEAN\]PRIMARY [BeamSize] /TRUNCATE Percent

Specify the truncation level. Default (in % of peak beam response) is given by the CLEAN\_TRUNCATE variable. Values are blanked beyond this.

## 18.21 READ

[CLEAN\]READ Buffer File [/COMPACT] [/FREQUENCY RestFreq]  
[/RANGE Min Max Type] [/NOTRAIL]

Read the specified internal buffer (BEAM, CCT, CGAINS, CLEAN, DIRTY, MASK, MODEL, PRIMARY, RESIDUAL, SKY, SUPPORT, SINGLEDISH, UV) from input File. Default extension is .uvt for UV, CGAINS and MODEL, and for the others, in order, .beam, .cct, .lmv-clean, .lmv, .msk, .lobe, .lmv-res, for Data Cubes when the extension is given as .fits (see HELP READ FITS for more details).

A subset of all available channels can be indicated through the /RANGE option, even for UV tables.

The corresponding buffer is available as a SIC image-like variable of the same name, so that one can use e.g. HEADER DIRTY command.

READ \* Name will attempt to read all existing files of same Name with the standard file types corresponding to the respective buffers.

The /COMPACT option is used to load the ACA-specific internal buffer used in the ALMA joint deconvolution method.

The /NOTRAIL allows to ignore trailing columns in UV data. This is normally not recommended and should be used for debug only. An exception is for "false" mosaics with just 1 field: see HELP READ /NOTRAIL for details.

### 18.21.1 READ Buffers

[CLEAN\]READ Buffer File [/COMPACT]

The recognized Buffer names for READ are:

BEAM	Synthesized Dirty beam
CCT	Clean Component list
CGAINS	Complex gains for APPLY command
CLEAN	Deconvolved Clean image
DIRTY	Dirty image
PRIMARY	Primary beam
RESIDUAL	Residual image
MASK	Spatial mask
MODEL	UV table for Clean components
SINGLEDISH	Single-Dish table or data cube
SKY	Primary beam-corrected deconvolved sky brightness
SUPPORT	Polygon enclosing the Support for Cleaning
UV_DATA	UV data table
UV_FIT	UV_FIT results table (for SHOW UV_FIT)

The MODEL UV table is for use in conjunction with commands in the CALIBRATE\ language, i.e. for Self-Calibration.

The following ones are allowed with the /COMPACT option

BEAM	Synthesized Dirty beam
DIRTY	Dirty image
PRIMARY	Primary beam
RESIDUAL	Residual image
UV_DATA	UV data table

### 18.21.2 READ FITS

[CLEAN\]READ Buffer File [/COMPACT]

For most buffers of type "Data Cube" (e.g. BEAM, CLEAN, DIRTY, PRIMARY, RESIDUAL, SINGLEDISH, SKY), the input File can be in FITS format. READ will check for the appropriate data format when appropriate. If the buffer does not accept FITS data format, an error message is issued.

UVFITS data format is not supported for UV data, because a number of important informations is sometimes stored in FITS Extensions. UVFITS format files should be converted to UV Tables in the GILDAS data format using the "@ fits\_to\_uvt" script.

### 18.21.3 READ Optimisation

Reading can be lengthy, especially for ALMA data. IMAGER attempts to minimize read operations by checking if anything has changed since the last command. This capability is enable if the SIC variable MAPPING\_OPTIMIZE is non zero, disabled otherwise.

Currently, the READ command always display a message about what reading may have been skipped, and whether this possible optimization has been overridden by user choice.

### 18.21.4 READ /COMPACT

[CLEAN\]READ Buffer File /COMPACT [/RANGE Min Max Type]

Read the specified internal buffer (UV, MODEL, BEAM, PRIMARY, DIRTY, CLEAN, MASK, CCT) from input File to the "compact array" data area.

### 18.21.5 READ /FREQUENCY

[CLEAN\]READ Buffer File /FREQUENCY RestFreq [/RANGE Min Max Type]

Read the specified internal buffer and reset the velocity scale to the corresponding rest frequencies. Velocities specified in the /RANGE Min Max VELOCITY option would then refer to this new frequency.

### 18.21.6 READ /NOTRAIL

[CLEAN\]READ Buffer File /NOTRAIL [/FREQUENCY Freq] [/RANGE Min Max Type]

When reading UV Tables, ignores any trailing column. Trailing columns normally appear for mosaics. However, ALMA sometimes uses known proper motions to shift (by small amounts) phase centers between two observing periods, yielding pseudo-mosaics with tiny (in general insignificant) displacements. The /NOTRAIL option allows to ignore these details.

### 18.21.7 READ /PLANES

[CLEAN\]READ Buffer File /PLANES Min Max

Read only the last axis "planes" between the First and Last implied by Min and Max. For an LMV-ordered cube, this would be equivalent to

READ Buffer File /RANGE Min Max CHANNEL

However, for transposed data cubes, VML or LVM-ordered for example, this is not true at all when a Frequency/Velocity axis is present: /RANGE would specify a subset of this(yet) axis, while /PLANES always indicate a subset of the 3rd axis of the cube.

Min and Max indicate offsets from Plane 1 and the number of planes Nplane. Thus Max can be negative: it then indicates Last = Nplane-Max. Also Min=0 and Max=0 implies loading all the channels.

### 18.21.8 READ /RANGE

```
[CLEAN\]READ Buffer File /RANGE Min Max Type
```

Load only the channels between the First and Last defined by Min Max and Type. Type can be CHANNEL, VELOCITY or FREQUENCY. If the Data cube has no Frequency/Velocity axis, only CHANNEL is allowed.

For type CHANNEL, Min and Max indicate offsets from Channel 1 and Channel Nchan (the number of channels in the data set). Thus Max can be negative: it then indicates Last = Nchan-Max. Also Min=0 and Max=0 implies loading all the channels.

The /RANGE option is not allowed for FITS files.

For UV tables with more than 1 Stokes parameter, which are **\*\*NOT\*\*** fully supported by IMAGER, the meaning of "channel" is ambiguous.

### 18.21.9 READ SINGLE

```
[CLEAN\]READ SINGLE File[.ext] [/RANGE Min Max Type]
```

Read the "Single Dish" data set. It can be a Class table (.tab), or a 3-D data cube (.lmv order). The data set is available as the SINGLE image variable.

If it is a 3-D data cube, the SHORT image variable is also defined (the data area is shared with that of the SINGLE imager variable, but the Headers are separate). If it is a Class table, the SHORT image becomes undefined. It will be computed by commands UV\_SHORT (see HELP UV\_SHORT Step\_1) or XY\_SHORT.

## 18.22 SUPPORT

```
[CLEAN\]SUPPORT [Polygon] [/CURSOR] [/MASK] [/PLOT] [/RESET] [/VARIABLE]
```

Define and/or plot the support inside which to search for CLEAN components. The support can be defined through a mask (see /MASK option) or a polygon, depending on the selected options. The /PLOT option can then be used to plot it.

A polygon stored in a file, or in a Sic variable (/VARIABLE option), can be loaded as the polygon support.

See also the [ADVANCED\]MASK command for a complementary way of defining supports, in particular 3-D supports.

### 18.22.1 SUPPORT /CURSOR

[CLEAN\]SUPPORT /CURSOR

With option /CURSOR, SUPPORT calls the interactive cursor to define the polygon summits. Type any key to go to next summit, D to correct the last one and type E to end the polygon definition. The last polygon side will then appear. The polygon definition may be aborted by typing Q. For graphical displays, you may use the mouse buttons for the commands. The left mouse button draws a vertex, the middle mouse button deletes the last vertex, and the right mouse button ends the polygon definition.

The resulting support is available in the Sic structure SUPPORT:

- SUPPORT%NXY [Integer] Number of summits
- SUPPORT%X [Double] X coordinates
- SUPPORT%Y [Double] Y coordinates

### 18.22.2 SUPPORT /MASK

[CLEAN\]SUPPORT /MASK or [ADVANCED\]MASK USE

Use the mask defined by READ MASK or by the MASK command as the clean support. This does not suppress the current polygon: it can be re-instated by a simple SUPPORT command with no argument.

The Mask can be a 3-D array: CLEAN will find out which mask plane must be used for each spectral channel.

Caution: [CLEAN\]READ MASK and [ADVANCED\]MASK command do not perform an implicit SUPPORT /MASK command. Only the ADVANCED\MASK USE command does it explicitly.

**18.22.3 SUPPORT /PLOT**

```
[CLEAN\]SUPPORT [Name] /PLOT
```

Plot the current (or specified) polygon, or plot the current mask (if it is 2-D only).

For 3-D masks, use the VIEW MASK command instead.

**18.22.4 SUPPORT /RESET**

```
[CLEAN\]SUPPORT /RESET
```

Reset any support to default. This deletes the current polygon support. This does not unload any mask defined by READ MASK. Such a mask can be re-instated by SUPPORT /MASK.

**18.22.5 SUPPORT /THRESHOLD**

```
[CLEAN\]SUPPORT /THRESHOLD [Raw Smooth [Length [Guard]]]
```

\*\*\* Obsolete - see [ADVANCED\]MASK THRESHOLD instead \*\*\*

**18.22.6 SUPPORT /VARIABLE**

```
[CLEAN\]SUPPORT VarName /VARIABLE
```

Load the support from the Sic variable VarName. VarName can be an array of the form:

```
VarName[NXY,2] Real or Double
```

or a structure of the form (i.e. same as output):

```
VarName%NXY Integer or Long
```

```
VarName%X[VarName%NXY] Real or Double
```

```
VarName%Y[VarName%NXY] Real or Double
```

**18.23 UV\_BASELINE**

```
[CLEAN\]UV_BASELINE [Degree] [/CHANNELS Channel_List]
[/FREQUENCY List Of Frequencies] [/RANGE Min Max [TYPE]]
[/VELOCITY List of Velocities] [/WIDTH Width [TYPE]]
[/FILE FileIn [FileOut]]
```

Subtract a continuum from a line UV data set, by fitting a baseline for

each visibility. The channels to be ignored in this process (i.e. the ones including the line emission) can be specified either by the /FREQUENCY or /VELOCITY options in combination with the /WIDTH option, or by a channel list with /CHANNELS or a range (of channels, frequencies or velocities) with /RANGE.

By default, the command works on the current UV data, unless the option /FILE is specified.

With no options (or with only /FILE), the command behaves as UV\_BASELINE /CHANNELS PreviewChannels. See UV\_PREVIEW for details.

### 18.23.1 UV\_BASELINE /CHANNELS

```
[CLEAN\]UV_BASELINE /CHANNELS Channel_List
```

Channel\_List must be a 1-D SIC variable containing the list of channels to filter out.

### 18.23.2 UV\_BASELINE /FILE

```
[CLEAN\]UV_BASELINE [Degree] [/CHANNELS Channel_List]
[/FREQUENCY List Of Frequencies] [/RANGE Min Max [TYPE]]
[/VELOCITY List of Velocities] [/WIDTH Width [TYPE]]
/FILE FileIn [FileOut]
```

Use the UV data in the file FileIn, and write the continuum-free visibilities in the file FileOut. If FileOut is not specified, "-line" is appended to the name indicated by FileIn.

### 18.23.3 UV\_BASELINE /FREQUENCY

```
[CLEAN\]UV_BASELINE /FREQUENCY F1 [... [Fn]] [/WIDTH Width [TYPE]]
```

Specify around which frequencies the line emission should be filtered. Frequencies F1 to Fn must be in MHz. The full width of the filtering window around every frequency can be set by option /WIDTH. The optional argument TYPE indicates the type of width: FREQUENCY (in MHz), VELOCITY (in km/s) or CHANNEL (no unit), the default being FREQUENCY. The default width is the current channel width.

Tip: it can be convenient to have a list of SIC variables containing the frequencies of the most intense spectral lines, e.g.

```
HCO10 = 89188.52
```



### 18.23.4 UV\_BASELINE /RANGE

```
[CLEAN\]UV_BASELINE /FREQUENCY F1 [... [Fn]] /RANGE Min Max [TYPE]
```

Indicate that channels between the First and Last defined by Min Max and Type contain line emission and should be ignored in the baseline fitting. Type can be CHANNEL, VELOCITY or FREQUENCY.

For type CHANNEL, Min and Max indicate offsets from Channel 1 and Channel Nchan (the number of channels in the data set). Thus Max can be negative: it then indicates Last = Nchan-Max. Also Min=0 and Max=0 implies loading all the channels.

### 18.23.5 UV\_BASELINE /VELOCITY

```
[CLEAN\]UV_BASELINE /VELOCITY V1 [... [Vn]] [/WIDTH Width [TYPE]]
```

Specify around which velocities the line emission should be filtered. Velocities V1 to Vn must be in km/s. The full width of the filtering window around every frequency can be set by option /WIDTH. The optional argument TYPE indicates the type of width: FREQUENCY (in MHz), VELOCITY (in km/s) or CHANNEL (no unit), the default being FREQUENCY. The default width is the current channel width.

### 18.23.6 UV\_BASELINE /WIDTH

```
[CLEAN\]UV_BASELINE /FREQUENCY F1 [... [Fn]] /WIDTH Width [TYPE]
```

Specify the full width of the window around every frequency given in the /FREQUENCY option. The optional argument TYPE indicates the type of width: FREQUENCY (in MHz), VELOCITY (in km/s) or CHANNEL (no unit), the default being FREQUENCY. The default width is the current channel width.

## 18.24 UV\_CHECK

```
[CLEAN\]UV_CHECK Beams|Nulls|Integration [/FILE FileIn]
```

Check current UV data for weight consistency, or the UV data in the specified file if the /FILE option is present.

#### BEAMS

List which channel range can be processed with the same synthesized beam. See HELP UV\_CHECK BEAM\_RANGE for further details.

#### NULLS

Check if there are null visibilities with non-zero weights, and flag them if found.

#### INTEGRATION

Attempt to estimate the integration time. This is done by comparing the time stamps of consecutive observations, unless an INTEGRATION column is present.

### 18.24.1 UV\_CHECK /FILE

```
[CLEAN\]UV_CHECK Beams|Nulls|Integration /FILE FileIn
```

Check the UV data in the specified file.

### 18.24.2 UV\_CHECK BEAM\_RANGES

UV\_CHECK BEAMS returns a variable named BEAM\_RANGES[3,Nbeam] where Nbeam is the number of different synthesized beams found in the UV data (based on the visibility weights).

BEAM\_RANGES[1,i] is the first channel of Beam number i  
 BEAM\_RANGES[1,2] is the last channel of Beam number i  
 BEAM\_RANGES[1,3] is the total weight of visibilities of Beam number i

BEAM\_RANGES is later used by UV\_PREVIEW to discard edge channels that often do not have the same weights as the bulk of channels.

Variable NBEAM\_RANGES indicates the number of beam ranges. It is -1 if UV\_CHECK has not yet been used.

Most automatic imaging processes will assume BEAM\_RANGES is relatively simple (2 edges and a dominant main range) and simply discard the edges if any, or complain if it is too complex.

For complex datasets with NBEAM\_RANGES greater than 2 or 3, BEAM\_RANGES could be used to segment the imaging and deconvolution process into ranges having a common beam. Setting MAP\_BEAM\_STEP to 1 is another possibility, but that creates 1 beam per channel, thus doubling the used space.

### 18.25 UV\_COMPRESS

```
[CLEAN\]UV_COMPRESS [Nc] [/CONTINUUM] [/FILE FileIn FileOut]
```

Resample the UV data by averaging NC adjacent channels.

With no /FILE option, the current UV table obtained by READ UV is resampled. All further UV commands work on the "Resampled" UV table. The "Resampled" UV table is a simple copy of the original one after a READ UV command, or after a UV\_RESAMPLE or UV\_COMPRESS commands with no arguments and no options.

With the /FILE option, the UV data is read from file FileIn and the resampled output is written in file FileOut.

With the /CONTINUUM option, the argument can be omitted, and the best value for Nc is derived from the current field of view, to avoid bandwidth smearing.

### 18.25.1 UV\_COMPRESS /CONTINUUM

```
[CLEAN\]UV_COMPRESS /CONTINUUM [/FILE FileIn FileOut]
```

Resample the UV data by averaging Nc adjacent channels. The value for Nc is derived from the current field of view, to avoid bandwidth smearing. This command is intended to provide a compact form of UV data for continuum-only imaging, through the UV\_MAP /CONTINUUM command. Contrary to the output of the UV\_CONTINUUM command, it is also suitable for Self-Calibration (and it is more compact).

With no /FILE option, the current UV table obtained by READ UV is resampled.

With the /FILE option, the UV data is read from file FileIn and the resampled output is written in file FileOut.

Caution: /CONTINUUM may not work with the /FILE option if the Minimum and Maximum baselines are not available in the FileIn header.

### 18.25.2 UV\_COMPRESS /FILE

```
[CLEAN\]UV_COMPRESS Nc /FILE FileIn FileOut
```

Use the UV data in the file FileIn, and write the data after averaging by NC adjacent channels in the file FileOut.

## 18.26 UV\_CONTINUUM

```
[CLEAN\]UV_CONTINUUM [Naver] [/INDEX Value [Frequency]]
[/RANGE Min Max TYPE]
```

Transform the (presumably spectral line) UV data set loaded by READ UV into a "continuum" data set.

The transformation selects line channels defined by the /RANGE option, average them by groups of Naver contiguous channels, and concatenate the resulting visibilities into a "continuum" UV table. If not present, Naver is derived from the current field of view MAP\_FIELD and required precision, MAP\_PRECIS to avoid bandwidth smearing at field edges.

For each output channel, and for all visibilities, the U and V coordinates are rescaled to the mean observing frequency, and the resulting (single-channel) visibilities are concatenated into the "continuum" UV data set. The continuum dataset becomes the current UV data. Flagged channels are ignored: this allows to mask channels containing spectral lines (see UV\_FILTER).

If no /RANGE option is defined, all channels are selected.

### 18.26.1 UV\_CONTINUUM /INDEX

```
[CLEAN\]UV_CONTINUUM Naver [First Last] /INDEX Value [Frequency]
```

Specify which spectral index to be used when scaling the visibilities as a function of frequency.

TO BE IMPLEMENTED: Frequency, if specified, will be used as a reference frequency instead of the mean observing frequency.

### 18.26.2 UV\_CONTINUUM /RANGE

```
[CLEAN\]UV_CONTINUUM Naver /RANGE Min Max TYPE
[/INDEX Value [Frequency]]
```

Indicate that channels between the First and Last defined by Min Max and Type should be considered to produce the output continuum UV table. Type can be CHANNEL, VELOCITY or FREQUENCY.

For type CHANNEL, Min and Max indicate offsets from Channel 1 and Channel Nchan (the number of channels in the data set). Thus Max can be negative: it then indicates Last = Nchan-Max. Also Min=0 and Max=0 implies all the channels.

## 18.27 UV\_EXTRACT

```
[CLEAN\]UV_EXTRACT /RANGE Min Max [TYPE] [/FILE FileIn [FileOut]]
```

Extract a subset of all available channels. The command works on the current UV buffer, unless the /FILE option is specified

### 18.27.1 UV\_EXTRACT /FILE

```
[CLEAN\]UV_EXTRACT /RANGE Min Max [TYPE] /FILE FileIn [FileOut]
```

Extract the specified range from the UV data in the file FileIn, and write the resulting visibilities in the file FileOut. If FileOut is not specified, "-ext" is appended to the name indicated by FileIn.

### 18.27.2 UV\_EXTRACT /RANGE

```
[CLEAN\]UV_EXTRACT /RANGE Min Max [TYPE] [/FILE FileIn [FileOut]]
```

Indicate that channels between the First and Last defined by Min Max and Type contain line emission and should be filtered out. Type can be CHANNEL, VELOCITY or FREQUENCY.

For type CHANNEL, Min and Max indicate offsets from Channel 1 and Channel Nchan (the number of channels in the data set). Thus Max can be negative: it then indicates Last = Nchan-Max. Also Min=0 and Max=0 implies all the channels.

## 18.28 UV\_FIELDS

```
[CLEAN\]UV_FIELDS RaVar DecVar [Unit] [/CENTER Ra Dec] /FILE File
```

Replace fields ID by Fields offsets in a Mosaic UV Table. This can only work for a Mosaic UV table with Fields offsets, or Phase center offsets. It cannot operate on a UV table with Pointing center offsets.

For files imported from UVFITS, the Fields offsets are found in the AIPS SU Table which is not decoded by the FITS command, but only through the DEFINE FITS command.

The UV\_FIELDS command allows to convert the Field IDs column of the UV table into Phase Offsets columns, and insert the proper coordinates. Unit specifies the unit of the RaVar and DecVar variables. It can be DEGREE, MINUTE, SECONDS, RADIAN or ABSOLUTE.

If ABSOLUTE, RaVar and DecVar are assumed to character variable arrays handling the Right Ascension and Declinations of the fields expressed in sexagesimal format.

The typical use is after a `DEFINE FITS A File.uvfits` command, which gives the (Ra,Dec) positions of the field centers in Degrees in `A%aips_su%col%raepo` and `A%aips_su%col%decepo` variables:

```
fits File.uvfits to File.uvt
define fits A File.uvfits
define double ra dec
define char*16 cra cdec
let cra ra /sexag d H
let cdec dec /sexag d d
compute ra mean a%aips_su%col%raepo
compute dec mean a%aips_su%col%decepo
!
uv_fields a%aips_su%col%raepo a%aips_su%col%decepo DEGREE -
  /FILE File.uvt /CENTER 'CRa' 'CDec'
!
```

This command is used in the `fits_to_uvt.ima` script. Note that a proper use also requires to set the reference coordinate to Ra and Dec consistently in the UV Table.

### 18.28.1 UV\_FIELDS /CENTER

```
[CLEAN\]UV_FIELDS RaVar DecVar [Unit] /CENTER Ra Dec /FILE File
```

Specify the reference center (Pointing and Phase) of the Mosaic UV table with Fields ID. In this case, RaVar and DecVar are true Ra and Dec (angles in the specified Unit), not Offsets. The Offsets are computed from the projection information in the UV table.

Ra and Dec should be in usual sexagesimal notation.

Without `/CENTER`, RaVar and DecVar are Offsets from the Phase and Pointing center of the Mosaic, as given in the UV data header, unless Unit is ABSOLUTE.

### 18.28.2 UV\_FIELDS /FILE

```
[CLEAN\]UV_FIELDS RaVar DecVar [Unit] [/CENTER Ra Dec] /FILE File
```

Modify the specified File.uvt handling the UV table.

If the option is not present, it would instead modify the current UV data in IMAGER. However, the READ command prevents to load UV tables that require the action of the UV\_FIELDS command, so in practice, the `/FILE` option becomes mandatory.

## 18.29 UV\_FILTER

```
[CLEAN\]UV_FILTER [/RESET] [/ZERO] [/CHANNELS Channel_List]
[/FREQUENCY List Of Frequencies] [/RANGE Min Max [TYPE]]
[/VELOCITY List of Velocities] [/WIDTH Width [TYPE]]
[/FILE FileIn [FileOut]]
```

"Filter" line emission, by flagging the corresponding channels. The channels can be specified either by the /FREQUENCY or /VELOCITY options in combination with the /WIDTH option, or by a channel list with /CHANNELS or a range (of channels, frequencies or velocities) with /RANGE.

By default, channels to be filtered are flagged (weights becoming negative). Option /ZERO can be used to erase them: weights and visibilities are set to zero, see `HELP UV_FILTER /ZERO`. On the contrary, option /RESET can be used to unflag them (and is thus conflicting with option /ZERO).

The command works on the current UV data, unless the option /FILE is specified.

With no options (except possibly /FILE and /ZERO), the command behaves as `UV_FILTER /CHANNELS PreviewChannels`. See `UV_PREVIEW` for details.

### 18.29.1 UV\_FILTER /CHANNELS

```
[CLEAN\]UV_FILTER [/RESET] [/ZERO] /CHANNELS Channel_List
```

Channel\_List must be a 1-D SIC variable containing the list of channels to filter out.

### 18.29.2 UV\_FILTER /FILE

```
[CLEAN\]UV_FILTER [/ZERO] [/CHANNELS Channel_List]
[/FREQUENCY List Of Frequencies] [/RANGE Min Max [TYPE]]
[/VELOCITY List of Velocities] [/WIDTH Width [TYPE]]
/FILE FileIn [FileOut]
```

Use the UV data in the file FileIn, and write the line-free visibilities in the file FileOut. If FileOut is not specified, "-cont" is appended to the name indicated by FileIn.

This option is conflicting with the /RESET option.

**18.29.3 UV\_FILTER /FREQUENCY**

```
[CLEAN\]UV_FILTER [/RESET] [/ZERO] /FREQUENCY F1 [...] [Fn]] [/WIDTH
Width]
```

Specify around which frequencies the line emission should be filtered. Frequencies F1 to Fn must be in MHz. The full width of the filtering window around every frequency can be set by option /WIDTH. The optional argument TYPE indicates the type of width: FREQUENCY (in MHz), VELOCITY (in km/s) or CHANNEL (no unit), the default being FREQUENCY. The default width is the current channel width.

Tip: it can be convenient to have a list of SIC variables containing the frequencies of the most intense spectral lines, e.g.

```
HCO10 = 89188.52
```

**18.29.4 UV\_FILTER /RANGE**

```
[CLEAN\]UV_FILTER [/RESET] [/ZERO] /RANGE Min Max [TYPE]
```

Indicate that channels between the First and Last defined by Min Max and Type contain line emission and should be filtered out. Type can be CHANNEL, VELOCITY or FREQUENCY.

For type CHANNEL, Min and Max indicate offsets from Channel 1 and Channel Nchan (the number of channels in the data set). Thus Max can be negative: it then indicates Last = Nchan-Max. Also Min=0 and Max=0 implies loading all the channels.

**18.29.5 UV\_FILTER /RESET**

```
[CLEAN\]UV_FILTER /RESET [/CHANNELS Channel_List]
[/FREQUENCY List Of Frequencies] [/RANGE Min Max [TYPE]]
[/VELOCITY List of Velocities] [/WIDTH Width [TYPE]]
```

Unflag the channels matching the selection criteria in the options. If no option is present, unflag channels in the PreviewChannels list, or all channels if that list does not exist.

The /RESET option is conflicting with /ZERO, and not valid in the /FILE mode either.

**18.29.6 UV\_FILTER /VELOCITY**

```
[CLEAN\]UV_FILTER [/RESET] /VELOCITY V1 [...] [Vn]] [/WIDTH Width
[TYPE]]
```



Specify around which velocities the line emission should be filtered. Velocities V1 to Vn must be in km/s. The full width of the filtering window around every frequency can be set by option /WIDTH. The optional argument TYPE indicates the type of width: FREQUENCY (in MHz), VELOCITY (in km/s) or CHANNEL (no unit), the default being FREQUENCY. The default width is the current channel width.

### 18.29.7 UV\_FILTER /WIDTH

```
[CLEAN\]UV_FILTER [/RESET] [/ZERO] /FREQUENCY F1 [... [Fn]] /WIDTH
Width [TYPE]
```

```
[CLEAN\]UV_FILTER [/RESET] [/ZERO] /VELOCITY V1 [... [Vn]] /WIDTH
Width [TYPE]
```

Specify the full width of the filtering window around every frequency given in the /FREQUENCY option or any velocity given in the /VELOCITY option. The optional argument TYPE indicates the type of width: FREQUENCY (in MHz), VELOCITY (in km/s) or CHANNEL (no unit), the default being FREQUENCY. The default width is the current channel width.

### 18.29.8 UV\_FILTER /ZERO

```
[CLEAN\]UV_FILTER [/RESET] /ZERO [/CHANNELS Channel_List]
[/FREQUENCY F1 [... [Fn]] [/VELOCITY V1 [... [Vn]]]
[/RANGE Min Max [TYPE]] [/WIDTH Width [TYPE]]
```

Erase filtered channels (set weight and visibilities to zero) rather than simply flagging them (weight set to negative value). This can be more convenient for further display, but is not reversible.

By default, channels to be filtered are flagged (weights becoming negative, and data can be unflagged by UV\_FLAG). Flagged channels are ignored in the averaging process, such as UV\_RESAMPLE or UV\_CONT. However, as UV\_MAP (in general) uses only one channel to define the weights for all others, these flagged channels will nevertheless appear in the imaged data cube.

See UV\_CHECK for information about handling flagged channels and different beams in a single UV table.

## 18.30 UV\_FLAG

```
[CLEAN\]UV_FLAG [/ANTENNA Iant] [/DATE ...] [/FILE FileIn [FileOut]]
```

[/RESET]

Without the /FILE option, display the current UV data and calls the cursor to interactively select a region where UV data will be flagged or unflagged (sign of weight is made negative or positive). The /RESET option is used to unflag the data.

UV data flagged using command UV\_FLAG can be saved on file with command WRITE UV File. Detailed information about the display control of the UV data may be found in the SHOW UV help.

See HELP UV\_FLAG /FILE for direct operation on a UV data file.

Subsequent mapping with UV\_MAP will ignore flagged data. However, for multi-channel imaging, the weight column is (by default) taken from one channel, so that channel-based flagging is will not be recognized in the default mode, but only in the "One Beam per Channel" mode.

### 18.30.1 UV\_FLAG /ANTENNA

```
[CLEAN\]UV_FLAG /ANTENNA Iant [/DATE ...] [/FILE FileIn [FileOut]]
[/RESET]
```

Restrict the flagging/unflagging to the specified antenna. Only one antenna at a time can be specified so far. If /ANTENNA is not present, the action concerns all antennas.

### 18.30.2 UV\_FLAG /DATE

```
[CLEAN\]UV_FLAG [/ANTENNA Iant] /DATE Date [/RESET]
```

Restrict the interactive flagging/unflagging to the specified Date.

```
[CLEAN\]UV_FLAG /DATE StartDate [StartUT [EndDate [EndUT]]]
/FILE FileIn [FileOut]] [/ANTENNA Iant] [/RESET]
```

With the /FILE option, the /DATE option has a more flexible syntax. It understands any of the following

/DATE StartDate	The whole date is flagged
from UT=0 to UT=24 h	
/DATE StartDate EndDate	The whole range of dates
from StartDate to EndDate	is flagged
/DATE StartDate StartUT EndUT	Time range from StartUT
to EndUT in StartDate	is flagged
/DATE StartDate StartUT EndDare EndUT	Time range from StartUT
in StartDate to EndUT in EndDate	is flagged

Date format is DD-MMM-YYYY, and Time is in hours, sexagesimal notation (hh:mm:ss.ss) allowed.

### 18.30.3 UV\_FLAG /FILE

```
[CLEAN\]UV_FLAG /FILE FileIn [FileOut] [/ANTENNA Iant] [/DATE ...]
[/RESET]
```

Flag data found in FileIn, and store the result in FileOut, or in place if FileOut is not specified. Note that the UV\_FLAG command has no memory: it cannot restore the flagging to a previous state, but only flag or unflag from the current flag state.

### 18.30.4 UV\_FLAG /RESET

```
[CLEAN\]UV_FLAG /RESET [/FILE FileIn [FileOut]] [/ANTENNA Iant]
[/DATE ...]
```

Unflag the specified range, instead for flagging it. Note that the UV\_FLAG command has no memory: it cannot restore the flagging to a previous state, but only flag or unflag from the current flag state.

### 18.30.5 UV\_FLAG CHANNEL

Channel range to be flagged/unflagged.

## 18.31 UV\_MAP

```
[CLEAN\]UV_MAP [CenterX CenterY Unit] [ANGLE AngleValue] [/FIELDS
FieldList] [/TRUNCATE Percent] [/RANGE Min Max Type] [/CONT [Naver]]
[/INDEX Alpha]
```

Compute a dirty map and beam from a UV data. UV data must have been loaded from a UV table by command "READ UV File". UV\_MAP processes single fields as well as Mosaics.

The user can control the algorithm through SIC variables. New values can be given using "LET VARIABLE value". For ease of use, and whenever it is possible, a sensible value of each parameter will automatically be computed from the context if the value of the corresponding variable is set to its default value, i.e. zero value and empty string. A few variables are initialized to "reasonable" values.

The arguments define the Map center and orientation (Projection system). Unit can be any of DEGREE, MINUTE, SECOND and RADIAN, or ABSOLUTE. In the latter case, CenterX should be the Right Ascension and CenterY the Declination in sexagesimal notation. Otherwise, they are offsets from the current projection center in the specified Unit.

AngleValue is the **\*\* absolute \*\*** rotation of the projection (counted East from North as usual), which means the angle between the Celestial North and the Y axis in the resulting image.

If no argument is given, UV\_MAP uses the variable MAP\_CENTER to derive the projection system. If it is empty, it does not change it.

[CLEAN\]UV\_MAP ?  
Will list all MAP\_\* variables controlling the UV\_MAP parameters

### 18.31.1 UV\_MAP Mosaics

[CLEAN\]UV\_MAP [[CenterX CenterY Unit] [ANGLE AngleValue]  
/FIELDS FieldList [/TRUNCATE Percent]

The UV data can be a Mosaic UV table. In this case, UV\_MAP will image the Mosaic, using appropriate primary beam size and truncation level.

By default, the primary beam size is taken from the telescope parameters, either as found in the telescope section of the UV table and the observing frequency (e.g. for ALMA it uses 1.13 Lambda/D). If absent, the telescope section information can be added by command SPECIFY TELESCOPE.

The truncation level for individual pointings is taken from variable MAP\_TRUNCATE or from the /TRUNCATE option argument. It should be 0 for high dynamic range. Non zero values may be used with caution in case of large pointing errors.

### 18.31.2 UV\_MAP /CONT

[CLEAN\]UV\_MAP [CenterX CenterY Unit] [ANGLE AngleValue] /CONT  
[Naver] [/INDEX Alpha] [/RANGE Min Max Type]

Produce a Continuum image (from all channels, or those selected by the specified Velocity, Frequency or Channel range (depending on Type) between Min Max when the option /RANGE is present), using a Multi-Frequency Synthesis, where (u,v) coordinates are scaled with Frequencies to produce an optimal beam.

Naver is the number of initial channels that will share the same (u,v) coordinates. If not present, it is computed from MAP\_FIELD and MAP\_CELL to limit bandwidth smearing.

In essence, UV\_MAP /CONT behaves as the combination of UV\_CONTINUUM followed by UV\_MAP, but the pseudo-continuum UV Table created by UV\_CONTINUUM is not kept by UV\_MAP /CONT.

A spectral index can be specified using option /INDEX.

### 18.31.3 UV\_MAP /FIELDS

```
[CLEAN\]UV_MAP [CenterX CenterY Unit] [ANGLE AngleValue]
/FIELDS FieldList [/TRUNCATE Percent]
```

For a Mosaic, only image the fields specified in a 1-D Integer variable FieldList, or in the explicit list given as argument to the /FIELDS option. SHOW FIELDS will highlight the list of fields selected by this command.

### 18.31.4 UV\_MAP /INDEX

```
[CLEAN\]UV_MAP [CenterX CenterY Unit] [ANGLE AngleValue] /CONT
[Naver] /INDEX Alpha [/RANGE Min Max Type]
```

Specify the spectral index to be used for Continuum imaging using a Multi-Frequency Synthesis method. This option is only valid with the /CONT option.

### 18.31.5 UV\_MAP /RANGE

```
[CLEAN\]UV_MAP [CenterX CenterY Unit] [ANGLE AngleValue]
/RANGE Min Max Type [/FIELDS FieldList] [/TRUNCATE Percent]
[/CONT [Naver]] [/INDEX Alpha]
```

Indicate that only channels between the First and Last defined by Min Max and Type should be considered to produce the image. Type can be CHANNEL, VELOCITY or FREQUENCY.

For type CHANNEL, Min and Max indicate offsets from Channel 1 and Channel Nchan (the number of channels in the data set). Thus Max can be negative: it then indicates Last = Nchan-Max. Also Min=0 and Max=0 implies all the channels.

This is a more convenient replacement of the deprecated MCOL variable.

**18.31.6 UV\_MAP /TRUNCATE**

```
[CLEAN\]UV_MAP [CenterX CenterY Unit] [ANGLE AngleValue]
/FIELDS FieldList /TRUNCATE Percent
```

For a Mosaic, truncate the individual pointings to the specified level (in percent). The default is to use MAP\_TRUNCATE.

**18.31.7 UV\_MAP Variables:**

```
[CLEAN\]UV_MAP ?
```

Will list all MAP\_\* variables controlling the UV\_MAP parameters.

The list of control variables is (by alphabetic order, with the corresponding old names used by Mapping on the right)

New names	[ unit]	-- Description --	% Old Name
BEAM_STEP	[ ]	Channels per dirty beam	% MAP_BEAM_STEP
MAP_CELL	[ arcsec]	Image pixel size	
MAP_CENTER	[ string]	RA, Dec of map center, and Position Angle	
MAP_CONVOLUTION	[ ]	Convolution function	% CONVOLUTION
MAP_FIELD	[ arcsec]	Map field of view	
MAP_POWER	[ ]	Maximum exponent of 3 and 5 allowed in MAP_SIZE	
MAP_PRECIS	[ ]	Fraction of pixel tolerance on beam matching	
MAP_ROBUST	[ ]	Robustness factor	% UV_CELL[2]
MAP_ROUNDING	[ ]	Precision of MAP_SIZE	
MAP_SIZE	[ ]	Number of pixels	
MAP_TAPEREXPO	[ ]	Taper exponent	% TAPER_EXPO
MAP_TRUNCATE	[ %]	Mosaic truncation level	
MAP_UVCELL	[ m]	UV cell size	% UV_CELL[1]
MAP_UVTAPER	[m,m,deg]	Gaussian taper	% UV_TAPER
MAP_VERSION	[ ]	Code version (0 new, -1 old)	

See HELP UV\_MAP Old\_names: for deprecated variable names.

**18.31.8 BEAM\_STEP**

```
BEAM_STEP Integer
```

Number of channels per synthesized beam plane.

Default is 0, meaning only 1 beam plane for all channels. N (>0) indicates N consecutive channels will share the same dirty beam.

A value of -1 can be used to compute the number of channels per beam plane that ensures that the angular scale does not deviate more than a fraction of the map cell at the map edge. This fraction is controlled by variable MAP\_PRECIS (default 0.1)

### 18.31.9 MAP\_CELL

MAP\_CELL[2]      Real

The map pixel size [arcsec]. It is recommended to use identical values in X and Y. A sampling of at least 5 pixel per beam is recommended to ease the deconvolution. Enter 0,0 to let the task find the best values.

### 18.31.10 MAP\_CENTER

MAP\_CENTER      Character String

Specify the Map center and orientation in the same way as the arguments of UV\_MAP.

LET MAP\_CENTER "ANGLE AngleValue"      ! Rotation angle

LET MAP\_CENTER "Ax Ay Unit"              ! Center position

where Unit is any of DEGREE, MINUTE, SECOND, RADIAN or ABSOLUTE. These two possibilities can be combined in any order:

LET MAP\_CENTER "ANGLE AngleValue Ax Ay Unit"

LET MAP\_CENTER "Ax Ay Unit ANGLE AngleValue"

In the latter case, the keyword ANGLE can be omitted.

For Unit ABSOLUTE, Ax Ay should be the RA and Dec in standard sexagesimal notation. As usual in SIC, keywords can be abbreviated provided they are not ambiguous.

### 18.31.11 MAP\_CONVOLUTION

MAP\_CONVOLUTION      Integer

Select the desired convolution function for gridding in the UV plane  
Choices are

- 0      Default (currently 5)
- 1      Boxcar
- 2      Gaussian
- 3      Sin(x)/x
- 4      Gaussian \* Sin(x)/x
- 5      Spheroidal

Spheroidal functions is the optimal choice. So we strongly discourage use of any other convolution function, which are here for tests only.

#### 18.31.12 MAP\_FIELD

MAP\_FIELD[2]      Real

Field of view in X and Y in arcsec. The field of view MAP\_FIELD has precedence over the number of pixels MAP\_SIZE to define the actual map size when both are non-zero.

#### 18.31.13 MAP\_POWER

MAP\_POWER[2]      Integer

Maximum exponent of 3 and 5 allowed in automatic guess of MAP\_SIZE. MAP\_SIZE is decomposed in  $2^k 3^p 5^q$ , and p and q must be less or equal to MAP\_POWER.

Default is 0: MAP\_SIZE is just a power of 2. A value of 1 allows approximation of any map size to 20 %, while a value of 2 allows 10 % approximation. Fast Fourier Transform are slightly slower with powers of 3 and 5, but limiting the map size can gain a lot in the Cleaning process (which can scale as  $\text{MAP\_SIZE}^4$ ).

#### 18.31.14 MAP\_PRECIS

MAP\_PRECIS      Real

Maximum mismatch in pixel at map edge between the true synthesized beam (which would have been computed using the exact channel frequency) and the computed synthesized beam with the mean frequency of the channels sharing the same beam. This is used (with the actual image size) to derive the actual number of channels that can share the same beam, i.e. the effective value of BEAM\_STEP when BEAM\_STEP is -1.

Default is 0.1

#### 18.31.15 MAP\_ROBUST



MAP\_ROBUST      Real

Robust weighting factor. A number between 0 and +infty.

Robust weighting gives the natural weight to UV cells whose natural weight is lower than a given threshold. In contrast, if the natural weight of the UV cell is larger than this threshold, the weight is set to this (uniform) threshold. The UV cell size is defined by MAP\_UVCELL and the threshold value is in MAP\_ROBUST.

0 means natural weighting, which is optimal for point sources. The Robust weighting factor controls the resolution: better resolution is obtained for small values (at the expense of noise), resolution approaching the natural weighting scheme for large values. Larger UV cell size give higher angular resolution (but again more noise).

MAP\_ROBUST around .5 to 1 is a good compromise between noise increase and angular resolution.

#### 18.31.16 MAP\_ROUNDING

MAP\_ROUNDING      Real

Maximum error which can be tolerated between optimal size ( given by MAP\_FIELD/MAP\_CELL) and its rounded value MAP\_SIZE (as a power of  $2^k 3^p 5^q$ ) when rounding by floor (thus limiting the field of view). If the rounding error becomes larger, rounding is made by ceiling, which guarantees a larger field of view, but leads to bigger images.

Default is 0.05.

#### 18.31.17 MAP\_SIZE

MAP\_SIZE[2]      Integer

Number of pixels in X and Y. It should preferentially be a power of two, (although this is not strictly required) to speed-up the FFT. MAP\_SIZE\*MAP\_CELL should be at least twice the size of the field-of-view (primary beam size for a single field). Enter 0,0 to let the command find a sensible map size.

MAP\_SIZE is not used if MAP\_FIELD is non zero.

Odd values are forbidden.

Default is 0,0, i.e. UV\_MAP will guess the most appropriate values which depend on MAP\_ROUNDING and MAP\_POWER.

#### 18.31.18 MAP\_TAPEREXPO

MAP\_TAPEREXPO     Real

Taper exponent. The default is 2 (indicating a Gaussian) but smoother or sharper functions can be used. 1 would give an Exponential, 4 would be getting close to square profile...

#### 18.31.19 MAP\_TRUNCATE

MAP\_TRUNCATE     Real

Individual beam truncation level in PerCent. Default value is 0. Current value can be overridden by option /TRUNCATE in commands UV\_MAP.

#### 18.31.20 MAP\_UVTAPER

MAP\_UVTAPER[3]   Real

Parameters of the tapering function (Gaussian if MAP\_TAPEREXPO = 2): major axis at 1/e level [m], minor axis at 1/e level [m], and position angle [deg].

#### 18.31.21 MAP\_UVCELL

MAP\_UVCELL     Real

UV cell size for robust weighting [m]. Should be of the order of half the dish diameter (7.5 m for NOEMA), or smaller or even larger. It controls the beam shape in Robust weighting.

#### 18.31.22 MAP\_VERSION

MAP\_VERSION     Integer

[EXPERT Only] Code indicating which version of the UV\_MAP and UV\_RESTORE algorithm should be used. 0 is optimal. -1 is the "historical" (pre-2016) version. 1 is an intermediate version used during multi-frequency beams development.

### 18.31.23 Old\_Names:

NAME is no longer used, and WEIGHT\_MODE is obsolete.

MAP\_RA [ hours] RA of map center  
 MAP\_DEC [ deg] Dec of map center  
 MAP\_ANGLE [ deg] Map position angle  
 MAP\_SHIFT [Yes/No ] Shift phase center

are obsolete, superseded by MAP\_CENTER. They are provided only for compatibility with older scripts.

MAP\_BEAM\_STEP is replaced by BEAM\_STEP. An alias is provided for compatibility reasons.

WCOL (the Weight channel) and MCOL[2] (the channel range) are obsolete also. WCOL has no meaning when more than 1 beam must be produced for all channels, and should be set to 0. MCOL is superseded by the /RANGE option facility.

NAME [ ] Label of the dirty image and beam plots  
 UV\_TAPER [m,m,deg] UV-apodization by convolution with a Gaussian  
 WEIGHT\_MODE [ ] Weighting mode (NA|UN)  
 UV\_CELL [m, ?? ] UV cell size and threshold for Robust weighting  
 MAP\_FIELD [ arcsec] Map field of view  
 MAP\_CELL [ arcsec] Map cell size  
 MAP\_SIZE [ pixels] Map size in pixels (if MAP\_FIELD is zero)  
 MCOL [ ] First and Last channel to map  
 WCOL [ ] Channel from which the weights are taken  
 CONVOLUTION [ ] Convolution function (5)  
 UV\_SHIFT [ ] Change the map phase center or map orientation?  
 MAP\_RA [ ] RA of map phase center  
 MAP\_DEC [ ] Dec of map phase center  
 MAP\_ANGLE [ deg] Map position angle  
 MAP\_BEAM\_STEP [ ] Number of channels per synthesized beam plane

### 18.31.24 convolution

Older variable name for MAP\_CONVOLUTION

**18.31.25 map\_angle**

MAP\_ANGLE      Real

Position   Angle of the direction which will become the apparent North in the map. Used only if MAP\_SHIFT is YES.

Superseded by MAP\_CENTER.

**18.31.26 map\_beam\_step**

MAP\_BEAM\_STEP   Integer

Older variable name for BEAM\_STEP

**18.31.27 map\_dec**

MAP\_DEC      Real

Dec of map center. Used only if MAP\_SHIFT is YES.

Superseded by MAP\_CENTER.

**18.31.28 map\_ra**

MAP\_RA      Real

RA of map center. Used only if MAP\_SHIFT is YES.

Superseded by MAP\_CENTER.

**18.31.29 mcol**

mcol[2]      Integer

[Deprecated] First and Last channel to image. Values of 0 mean imaging all the planes. See UV\_MAP /RANGE for a more flexible way to specify the channel range.

**18.31.30 uv\_cell**

Older variables for MAP\_UVCELL (uv

**18.31.31 uv\_shift**

Older variable name of MAP\_SHIFT (this one is also obsolescent)

**18.31.32 uv\_taper**

Older variable name of MAP\_UVTAPER

**18.31.33 taper\_expo**

Older variable name for MAP\_TAPEREXPO

**18.31.34 wcol**

WCOL       Integer

[Obsolescent] The channel from which the weight should be taken. WCOL set to 0 means using a default channel. WCOL has no real meaning in all cases where more than one beam is computed for all channels.

**18.31.35 weight\_mode**

weightde     Character

[Deprecated] Weighting mode: Natural (optimum in terms of sensitivity) or robust (usually lower sidelobes and higher spatial resolution) weighting. This was needed in Mapping to toggle between Natural and Robust weighting, while IMAGER does that based on MAP\_ROBUST value.

### 18.32 UV\_RESAMPLE

```
[CLEAN\]UV_RESAMPLE [Nc Ref Val Inc] [/FILE FileIn FileOut] [/LIKE Mold]
```

With no option, resample the UV data loaded by READ UV on a different velocity scale. All other UV commands except UV\_COMPRESS work on the "Resampled" UV table. The output spectral sampling is defined by

```
Nc    new number of channels
Ref   New reference pixel
Val   New velocity at reference pixel
Inc   Velocity increment
```

Any argument can be set to \* for an automatic determination based on the values of the other arguments. The automatic determination of NC preserves the velocity coverage.

The "Resampled" UV table is a simple copy of the original one after a READ UV command, or after a UV\_RESAMPLE or UV\_COMPRESS command without arguments.

With the /FILE option, the internal buffers are not used: the UV data is read from file FileIn and the resampled output is written in file FileOut. In this case, the /LIKE option can be used to define the spectral sampling as identical to the Mold file.

#### 18.32.1 UV\_RESAMPLE /FILE

```
[CLEAN\]UV_RESAMPLE [Nc Ref Val Inc] /FILE FileIn FileOut [/LIKE Mold]
```

Use the UV data in the file FileIn, and write the spectrally resampled UV data in the file FileOut.

In this case, the /LIKE option can be used to define the spectral sampling as identical to the Mold file, instead of specifying it as arguments to the command.

#### 18.32.2 UV\_RESAMPLE /LIKE

```
[CLEAN\]UV_RESAMPLE /FILE FileIn FileOut /LIKE Mold
```

Use the UV data in the file FileIn, and write the spectrally resampled UV data in the file FileOut. The resampled FileOut will spectrally conform the Mold UV table specified in the /LIKE argument.

### 18.33 UV\_RESIDUAL

[CLEAN\]UV\_RESIDUAL [MODE] [Arg1 ... ArgN] [/FIELDS List]

This command subtract Clean components OR fit results from the last UV\_FIT command, depending on specified argument MODE if present (can be CLEAN or UV\_FIT), or on whether CLEAN (or its specialized versions HOG-BOM, CLARK, etc...) or UV\_FIT was done last if not. The residual UV data are available in SIC structure UV\_RESIDUAL, and can be written by WRITE UV\_RESIDUAL command.

The UV\_RESIDUAL data can also be selected for further imaging by UV\_MAP (and thus UV\_RESTORE) or displayed by SHOW UV using command UV\_SELECT. MODEL and UV\_RESIDUAL are complementary commands ( $UV\_DATA = UV\_MODEL + UV\_RESIDUAL$ ); see HELP UV\_RESIDUAL Note however.

For the Clean component the syntax is

[CLEAN\]UV\_RESIDUAL [CLEAN] [Niter]

that subtracts the Niter first (default all) Clean Components from the UV data.

For the UV\_FIT results, Clean component the syntax is

[CLEAN\]UV\_RESIDUAL [UV\_FIT] [F1 .. Fn]

that subtracts the F1 to Fn fitted functions (default all) from the UV data.

#### 18.33.1 UV\_RESIDUAL Note

UV\_RESIDUAL does not yet have the /MINVAL option of command MODEL.

### 18.34 UV\_RESTORE

[CLEAN\]UV\_RESTORE [/COPY] [/SPEED Mode]

Create a Clean image from the current UV data set and the Clean Component list. The Clean Components are subtracted from the UV data set, and these residuals are gridded and Fourier transformed to compute the Residual image. This Residual image is added to the Gaussian beam convolved image of the sum of Clean components. The results are similar to those of MX, since only the residual are aliased.

This command can be used with all methods (HOGBOM, CLARK, MULTI, SDI) except for MRC which has no notion of Clean Components.

**18.34.1 UV\_RESTORE /COPY**

[CLEAN\]UV\_RESTORE /COPY [/SPEED Mode]

--- Obsolescent --- Reserved for debugging ---

The /COPY option controls whether array copys or pointers are used for some internal buffers. The option may be removed without further notice.

**18.34.2 UV\_RESTORE /SPEED**

[CLEAN\]UV\_RESTORE /SPEED Mode [/COPY]

Create a Clean image from the current UV data set and the Clean Component list, using the specified Mode to remove the Clean Components before imaging the residuals.

The argument Mode may be one of the following keyword:

AUTO Automatically select the "fastest" method, according to the current number of Visibilities and Clean components.

FFT Subtract Clean Components by FFT and interpolation onto individual visibilities.

PRECIS Subtract the Clean Components by simple Sin/Cos phase terms for each visibility

The PRECIS mode is faster for a small number of visibilities and Clean components, while the FFT mode is faster for large ones.

Instead of the above keywords, Mode may also be a number which specifies when the AUTO mode should switch from PRECIS mode to FFT mode. The default number to control the AUTO mode is 200 Millions (product of the number of visibilities and average number of Clean components per channel). This value is "sticky": if changed by /SPEED, the new values is retained until next change.

**18.35 UV\_REWEIGHT**

[CLEAN\]UV\_REWEIGHT MODE [Args...] [/RANGE Min Max Type]  
[/FLAG Threshold]

Compute and/or Apply a scale factor to the weights of the current UV data. Can be used to patch e.g. JVLA data files which may have only relative weights, not absolute values indicating the noise.

MODE can be APPLY, DO, ESTIMATE or TIME.



### 18.35.1 UV\_REWEIGHT APPLY

[CLEAN\]UV\_REWEIGHT APPLY Factor

Apply the specified scale Factor to the weights. Factor can be \* to used the last derived scale factor from command UV\_REWEIGHT ESTIMATE. This factor is set to 1.0 by command UV\_REWEIGHT APPLY, so that repetitive use of the APPLY \* mode no longer affects the data.

### 18.35.2 UV\_REWEIGHT DO

[CLEAN\]UV\_REWEIGHT DO [Tolerance [Printout]] [/RANGE Min Max Type]  
[/FLAG Threshold]

Derive the scale factor from the noise statistics over the channels, and use it to rescale the weights. The noise statistic is derived from the real and imaginary parts separately, taking mean value, or the minimum of the twos when the mean/min ratio is smaller than specified Tolerance (default is 1.2).

The /FLAG option indicates whether data with highly deviating weights should be flagged. UV\_REWEIGHT DO combines the two actions of UV\_REWEIGHT ESTIMATE (or TIME) and UV\_REWEIGHT APPLY, but with a control over these outliers (that are not identified by APPLY).

Mode DO uses the ESTIMATE method if the number of channels is > 16, the TIME method if not.

Printout is a number indicating to print some correction factors every Printout visibility (no print if 0, the default) (for ESTIMATE method only).

### 18.35.3 UV\_REWEIGHT ESTIMATE

[CLEAN\]UV\_REWEIGHT ESTIMATE [Tolerance [Printout]] [/RANGE Min Max Type]

Derive the scale factor from the noise statistics derived from the rms individual visibilities over the specified channels. The noise statistic is derived from the real and imaginary parts separately, taking mean value, or the minimum of the twos when the mean/min ratio is smaller than specified Tolerance (default is 1.2).

Printout is a number indicating to print some correction factors every Printout visibility (no print if 0, the default).

**18.35.4 UV\_REWEIGHT TIME**

```
[CLEAN\]UV_REWEIGHT TIME [Tolerance] [/RANGE Min Max Type]
```

Derive the scale factor from the noise statistics derived from consecutive visibilities, considering the specified channel range. The noise statistic is derived from the real and imaginary parts separately, taking mean value, or the minimum of the twos when the mean/min ratio is smaller than specified Tolerance (default is 1.2).

The UV data is first baseline-time sorted to ensure that all UV data points of the UV track for any antenna pair are consecutive.

**18.35.5 UV\_REWEIGHT /RANGE**

```
[CLEAN\]UV_REWEIGHT DO|ESTIMATE|TIME [Tolerance [Printout]] [/FLAG
Threshold]
/RANGE Min Max [Min Max [...]] Type
```

Specify the spectral range(s) defining the channels to use in the noise estimates. More than 1 range can be specified if the Mode is not TIME.

/RANGE can not be used with keyword APPLY.

**18.35.6 UV\_REWEIGHT /FILE**

```
[CLEAN\]UV_REWEIGHT DO|ESTIMATE|TIME [Tolerance [Printout]] [/FLAG
Threshold]
/RANGE Min Max [Min Max [...]] Type
```

**18.35.7 UV\_REWEIGHT /FLAG**

```
[CLEAN\]UV_REWEIGHT DO [Tolerance [Printout]] /FLAG Threshold
[/RANGE Min Max Type]
```

The /FLAG option indicates whether data with highly deviating weights should be flagged. UV\_REWEIGHT DO combines the two actions of UV\_REWEIGHT ESTIMATE and UV\_REWEIGHT APPLY, but with a control over these outliers (that are not identified by APPLY).

Default Threshold is 3, i.e. data are considered as outliers if their re-scale factor is more than 3 times above (or below) the median value. This is adequate to spot bad data.

/FLAG is only valid for keyword DO.

### 18.36 UV\_SHIFT

```
[CLEAN\]UV_SHIFT [CenterX CenterY UNIT] [ANGLE Angle] [/FILE
FileInOut]
```

Shift the current (if no /FILE option is present) or specified (if the /FILE option is here) UV table (single field or mosaic) to a common phase center and/or rotate it.

Angle is desired position angle of the Celestial North from the Y axis (counted positive towards East, i.e. counter-clockwise in usual astronomical images), in Degree. It is thus an absolute value.

If UNIT is ABSOLUTE, CenterX and CenterY are absolute coordinates in usual sexagesimal notation.

If not, CenterX and CenterY are offsets in the specified angular unit (SECOND, MINUTE, DEGREE or RADIAN).

Although UV\_MAP also provides a direct possibility to re-center the image on a specified projection (phase) center combined with a rotation of the main axes, the modified visibilities cannot be saved on file. It is sometimes required to do this for specific use. UV\_SHIFT provides this possibility, and the shifted UV table can be written using command WRITE UV.

UV\_DEPROJECT includes the UV\_SHIFT capabilities, but also has additional functions, and a different syntax.

#### 18.36.1 UV\_SHIFT /FILE

```
[CLEAN\]UV_SHIFT [CenterX CenterY UNIT] [ANGLE Angle] /FILE
FileInOut
```

Shift and/or rotate the UV table specified in the /FILE option (single field or mosaic) to a common phase center and given orientation.

Warning: Rotated Mosaics cannot yet be saved. IRAM has not decided upon a convention for storing this information.

### 18.37 UV\_SMOOTH

```
[CLEAN\]UV_SMOOTH Nc [/ASYMMETRIC] [/FILE FileIn FileOut]
```

Smooth by NC channels a UV data set. UV\_SMOOTH differs from UV\_COMPRESS because it keeps the original spectral sampling. The resulting UV data is thus oversampled by NC channels.

Unless the /ASYMMETRIC option is present, the smoothing is symmetric, to ensure that the spectral sampling is preserved. This is implicit when Nc is odd, but for even values of Nc, it is done by smoothing by Nc+1 channels, and giving the edge channels of the smoothing kernel a half-weight. The effective bandwidth of each smoothed channel is still Nc times the original one.

As a result, UV\_SMOOTH 2 is equivalent to a Hanning smoothing.

With no /FILE option, the current UV table obtained by READ UV is resampled. All further UV commands work on the "Resampled" UV table. The "Resampled" UV table is a simple copy of the original one after a READ UV command, or after a UV\_RESAMPLE or UV\_COMPRESS commands with no arguments and no options.

With the /FILE option, the UV data is read from file FileIn and the resampled output is written in file FileOut.

### 18.37.1 UV\_SMOOTH /ASYMMETRIC

```
[CLEAN\]UV_SMOOTH Nc /ASYMMETRIC [/FILE FileIn FileOut]
```

Make no attempt to preserve the spectral sampling when Nc is even: the reference channel is then shifted by half the channel spacing.

For odd Nc, the smoothing is naturally symmetric, so the option has no impact.

### 18.37.2 UV\_SMOOTH /FILE

```
[CLEAN\]UV_SMOOTH Nc /FILE FileIn FileOut [/ASYMMETRIC]
```

Read the UV data in the file FileIn, and write the data after averaging by NC adjacent channels in the file FileOut.

## 18.38 UV\_SPLIT

```
[CLEAN\]UV_SPLIT [Degree [Compress]] /FILE FileIn [FileLine [File-
```

```
Cont]]
[/CHANNELS Channel_List]
[/FREQUENCY List Of Frequencies] [/RANGE Min Max [TYPE]]
[/VELOCITY List of Velocities] [/WIDTH Width [TYPE]]
```

"Split" the UV table found in file FileIn into a Continuum-free one (FileLine) and a Line-free continuum one (FileCont), using the ranges specified by one of the other options to indicate where the line emission is (see UV\_BASELINE and UV\_FILTER for details). The channels can be specified either by the /FREQUENCY or /VELOCITY options in combination with the /WIDTH option, or by a channel list with /CHANNELS or a range (of channels, frequencies or velocities) with /RANGE.

Degree is the baseline fit degree (0 or at most 1). Compress is the number of line channels averaged together while producing the pure continuum (Line-free) visibilities.

The command only works with files: option /FILE is mandatory.

With only /FILE as option, the command behaves as UV\_SPLIT /FILE FileIn [FileLine [FileCont]] /CHANNELS Preview%Channels. See UV\_PREVIEW for details about Preview%Channels.

### 18.38.1 UV\_SPLIT /CHANNELS

```
[CLEAN\]UV_SPLIT [Degree [Compress]] /FILE FileIn [FileLine [File-
Cont]]
/CHANNELS Channel_List
```

Channel\_List must be a 1-D SIC variable containing the list of channels where line emission is assumed to be.

### 18.38.2 UV\_SPLIT /FILE

```
[CLEAN\]UV_SPLIT [Degree [Compress]] /FILE FileIn [FileLine [File-
Cont]]
[/FREQUENCY List Of Frequencies] [/RANGE Min Max [TYPE]]
[/VELOCITY List of Velocities] [/WIDTH Width [TYPE]]
/FILE FileIn [FileOut]
```

Use the UV data in the file FileIn, and write the continuum-free visibilities in the file FileLine, and the line-free visibilities in FileCont. If not specified, FileLine (resp FileCont) is derived from FileIn by appending "-line" (resp "-cont") to the filename.

### 18.38.3 UV\_SPLIT /FREQUENCY

```
[CLEAN\]UV_SPLIT [Degree [Compress]] /FILE FileIn [FileLine [File-
Cont]]
/FREQUENCY F1 [... [Fn]] [/WIDTH Width]
```

Specify around which frequencies the line emission should be found. Frequencies F1 to Fn must be in MHz. The full width of the window around every frequency can be set by option /WIDTH. The optional argument TYPE indicates the type of width: FREQUENCY (in MHz), VELOCITY (in km/s) or CHANNEL (no unit), the default being FREQUENCY. The default width is the current channel width.

Tip: it can be convenient to have a list of SIC variables containing the frequencies of the most intense spectral lines, e.g.

```
HCO10 = 89188.52
```

### 18.38.4 UV\_SPLIT /RANGE

```
[CLEAN\]UV_SPLIT [Degree [Compress]] /FILE FileIn [FileLine [File-
Cont]]
/RANGE Min Max [TYPE]
```

Indicate that channels between the First and Last defined by Min Max and Type contain line emission. Type can be CHANNEL, VELOCITY or FREQUENCY.

For type CHANNEL, Min and Max indicate offsets from Channel 1 and Channel Nchan (the number of channels in the data set). Thus Max can be negative: it then indicates Last = Nchan-Max. Also Min=0 and Max=0 implies loading all the channels.

### 18.38.5 UV\_SPLIT /VELOCITY

```
[CLEAN\]UV_SPLIT [Degree [Compress]] /FILE FileIn [FileLine [File-
Cont]]
/VELOCITY V1 [... [Vn]] [/WIDTH Width [TYPE]]
```

Specify around which velocities the line emission should be found. Velocities V1 to Vn must be in km/s. The full width of the window around every frequency can be set by option /WIDTH. The optional argument TYPE indicates the type of width: FREQUENCY (in MHz), VELOCITY (in km/s) or CHANNEL (no unit), the default being FREQUENCY. The default width is the current channel width.

### 18.38.6 UV\_SPLIT /WIDTH

```
[CLEAN\]UV_SPLIT [Degree [Compress]] /FILE FileIn [FileLine [File-
Cont]]
/FREQUENCY F1 [... [Fn]] /WIDTH Width [TYPE]
```

```
[CLEAN\]UV_SPLIT [Degree [Compress]] /FILE FileIn [FileLine [File-
Cont]]
/VELOCITY V1 [... [Vn]] /WIDTH Width [TYPE]
```

Specify the full width of the window around every frequency given in the /FREQUENCY option or any velocity given in the /VELOCITY option. The optional argument TYPE indicates the type of width: FREQUENCY (in MHz), VELOCITY (in km/s) or CHANNEL (no unit), the default being FREQUENCY. The default width is the current channel width.

## 18.39 UV\_STAT

```
[CLEAN\]UV_STAT Mode [Start [Step]]
```

UV\_STAT allows the astronomer to select the best weighting and imaging parameters according to its personal trade off between angular resolution, sensitivity and field of view.

Argument Mode describes the action. Default is ALL, equivalent to HEADER+ADVISE. See HELP UV\_STAT Argument for details.

### 18.39.1 UV\_STAT Casa

CASA and GILDAS handle the weighting scheme slightly differently and with different conventions for the Robust parameter values.

CASA uses only Briggs weighting, while IMAGER offers the Briggs weighting scheme (obtained for MAP\_ROBUST < 0) and a different, more progressive, weighting (obtained for MAP\_ROBUST > 0).

For MAP\_ROBUST < 0, the corresponding CASA Briggs value can be obtained by adding 2.

In addition, CASA apparently uses a default value for the size of the UV cell in Briggs weighting which is about the dish diameter(\*). If MAP\_UVCELL is 0, IMAGER will use the same default value. Otherwise, IMAGER will use the specified user input.

(\*) The default value quoted before is valid for a single field. Howev-

er, the documentation is unclear in this respect and suggests that the UV cell size depends on the imaged field size. This would be strange, though. What happens for mosaics is even less clear.

### 18.39.2 UV\_STAT Mosaics

UV\_STAT handles Mosaic like Single-Field for the weighting (BEAM, BRIGGS, TAPER and WEIGHT arguments): all visibilities are considered, instead of those of just one among the various fields. Accordingly, the predicted beam sizes are often underestimated compared to what UV\_MAP and FIT commands would yield.

For a fine adjustment of the beam shape and size, it is recommended to verify using UV\_MAP and FIT commands and iterate if needed.

### 18.39.3 UV\_STAT Arguments:

[CLEAN\]UV\_STAT Mode [Start [Step]]

Argument Mode describes the action. Possible values are

ADVISE	Suggest values for Map size, Map field and Pixel size
ALL	As HEADER + ADVISE
BEAM	Evaluate (and optionally display) the synthesized beam
BRIGGS	Estimate beam size as function of Briggs robust parameter
CELL	Estimate beam size as function of UV cell size
DEFAULT	Reset UV_MAP parameters to Default values
HEADER	Display detailed UV header
RESET	Reset UV_MAP parameters to previous Values
SETUP	Take suggested values for Map size, Map field and Pixel size
TAPER	Estimate beam size as function of UV Taper
WEIGHT	Estimate beam size as function of Gildas robust parameter

The default value is ALL, which makes the same action as HEADER + ADVISE combined.

### 18.39.4 ADVISE

[CLEAN\]UV\_STAT ADVISE

Display the recommended image and pixel sizes, independently of the current values of MAP\_FIELD, MAP\_SIZE and MAP\_CELL.



### 18.39.5 ALL

```
[CLEAN\]UV_STAT ALL
```

Display the UV header and a few more associated values, like the recommended image and pixel sizes. Equivalent to HEADER + ADVISE

### 18.39.6 BEAM

```
[CLEAN\]UV_STAT BEAM [Show]
```

Evaluate the expected synthesized beam size and orientation, based on current imaging parameters MAP\_UVCELL, MAP\_ROBUST, MAP\_UVTAPER.

If argument Show is present, the synthesized beam is also displayed. A fast gridding is used for this command to minimize computing time, so the actual synthesized beam produced by UV\_MAP will be (very slightly) different. This does not significantly affect the beam size.

### 18.39.7 BRIGGS

```
[CLEAN\]UV_STAT BRIGGS
```

Beam sizes and noise level (in flux and brightness) will be computed for 9 different "robust" weighting parameters using the Briggs method. The Briggs parameters range from -4 (nearly uniform weighting) to 0 (natural weighting) (values are shifted by -2 compared to the Briggs parameters in CASA). The taper is taken from variable UV\_TAPER. The UV cell size is specified by MAP\_UVCELL in m.

See HELP UV\_STAT Casa for details about Briggs parameter vs Robust parameter.

### 18.39.8 CELL

```
[CLEAN\]UV_STAT CELL [Start [Step]]
```

Predict the synthesized beam, expected noise level, and recommended pixel size for different values of the uv cell size for current robust weighting and taper parameters.

### 18.39.9 DEFAULT

[CLEAN\]UV\_STAT DEFAULT

Reset MAP\_SIZE, MAP\_CELL, MAP\_FIELD and MAP\_UVCELL to their Default values (all 0). Robust parameter and Tapers are not changed. Command UV\_STAT RESET does a slightly different job.

### 18.39.10 HEADER

[CLEAN\]UV\_STAT HEADER

Display a brief summary of the UV data: number of antennas, observing dates, baseline ranges, spectroscopic information.

### 18.39.11 RESET

[CLEAN\]UV\_STAT RESET

Reset MAP\_SIZE, MAP\_FIELD and MAP\_CELL to their previous values after a UV\_STAT SETUP. This is different from the UV\_STAT DEFAULT command.

### 18.39.12 SETUP

[CLEAN\]UV\_STAT SETUP

Compute the recommended values for the imaging: image size, pixel size, field of view, largest angular scale, etc..., and set the corresponding MAP\_variables (MAP\_SIZE, MAP\_FIELD and MAP\_CELL) to these values if they were not previously specified.

### 18.39.13 TAPER

[CLEAN\]UV\_STAT TAPER [Start [Step]]

For TAPER, beam sizes and noise level (in flux and brightness) will be computed for 9 different tapers (from Start to  $\text{Start} \times \text{Step}^9$ ). Default value for Step is  $\sqrt{2}$ , Default value for Start is 50 m. Weighting mode, UV cell size and "robust" parameter are taken from variable MAP\_UVCELL and MAP\_ROBUST (i.e. one can combine Robust weighting and Tapering).

### 18.39.14 WEIGHT

[CLEAN\]UV\_STAT WEIGHT [Start [Step]]

For WEIGHT, beam sizes and noise level (in flux and brightness) will be computed for 9 different "robust" weighting parameters (from Start to Start\*Step^9). Default value for Step is sqrt(10), and default value for Start is derived to center the "robust" parameter values around 1. UV cell size is taken from variable MAP\_UVCELL, and Taper is taken from variable UV\_TAPER.

## 18.40 UV\_TIME

```
[CLEAN]UV_TIME [?|Time] [/Weight Wcol] [/FILE FileIn]
```

Average in time the current UV data set to reduce the number of visibilities. Time must be in seconds. If not specified, an automatic guess is performed based on Nyquist criterium using the antenna size and baseline lengths.

With a ? as argument, return the longest reasonable time. This time depends on the field of view (that can be controlled by MAP\_FIELD) and the requested precision (controlled by MAP\_PRECIS). It is also limited by the UV cell size for beam forming (MAP\_UVCELL).

### 18.40.1 UV\_TIME /WEIGHT

```
[CLEAN]UV_TIME Time /WEIGHT Wcol
```

Select the weight column. Default is 0.

### 18.40.2 UV\_TIME /FILE

```
[CLEAN]UV_TIME [?|Time] /FILE FileIn [FileOut] [/Weight Wcol]
```

Work on the specified input (FileIn) and output (FileOut) for the time compression instead of the UV buffer. FileIn must exist.

## 18.41 UV\_TRIM

```
[CLEAN\]UV_TRIM Action [/FILE FileIn [FileOut]]
```

Trim the UV data of useless information, according to the Action keyword. Action can be

ANY	Remove visibilities that have at least one channel flagged
FLAG	Remove visibilities where all channels are flagged
TRAIL	Remove trailing columns

The command works on the current UV data set, unless the /FILE option is present.

### 18.41.1 UV\_TRIM /FILE

[CLEAN]UV\_TRIM Action /FILE FileIn [FileOut]

Trim the UV data of useless information, according to the Action keyword. The UV data is taken from file FileIn and written on FileOut (default: overwrite FileIn).

### 18.42 UV\_TRUNCATE

[CLEAN]UV\_TRUNCATE Max [Min]

Truncate the UV data, by removing baselines out of the specified range Min (default 0) and Max (in meter).

### 18.43 WRITE

[CLEAN\]WRITE Name File [Format] [/APPEND] [/RANGE Start End Kind] [/REPLACE] [/TRIM [Any]]

WRITE the buffer specified by Name (UV, CGAINS, and BEAM, PRIMARY, DIRTY, CLEAN, RESIDUAL, SUPPORT, CCT, SKY) onto a File. Default extensions are .uvt for UV and CGAINS and .beam, .lmv, .lobe, .lmv-clean, .lmv-res, .pol, .cct, and lmv-sky respectively for the next ones. If Name does not refer to a known buffer, but to a SIC Image variable, this variable is written. The default extension is then .gdf.

Format is an optional argument indicating the output file data format. It can take the value GILDAS (the default) or FITS. FITS format is allowed for UV data and images, but not for tables like the Clean Component, or self-calibration results. Options /APPEND and /REPLACE are not useable for FITS format.

For UV data, the flagged data are written by default. They may be omitted using the /TRIM option.

WRITE \* File can be used to write all modified image-like buffers (not the UV tables) under a common File name. This typically include .beam, .lmv and .lmv-clean, but also the .lmv-sky file if the PRIMARY command has been used after deconvolution.

Options /APPEND and /REPLACE are mutually exclusive, and in general used with the /RANGE option.

#### 18.43.1 WRITE Format

```
[CLEAN\]WRITE Name File FITS|GILDAS [/RANGE Start End Kind] [/TRIM  
[Any]]
```

The 3rd argument of the WRITE command is an optional keyword indicating the output file data format. It can take the value GILDAS (the default) or FITS.

FITS format is allowed for UV data and Images (n-D hypercubes), but not for Tables like the Clean Component Tables, or self-calibration results.

Options /APPEND and /REPLACE are not useable for FITS format.

#### 18.43.2 WRITE /RANGE

```
[CLEAN\]WRITE Buffer File [Format] /RANGE Start End Kind [/APPEND  
[/REPLACE]]
```

A range of planes can be specified through /RANGE option. Kind is the unit of the Start-End values: CHANNEL, VELOCITY, or FREQUENCY. This is also possible for UV data, except for FITS output format.

The Buffer name must be specified (\* is not valid here).

#### 18.43.3 WRITE /APPEND

```
[CLEAN\]WRITE Buffer File /APPEND [/RANGE Start End Kind]
```

The selected channels are appended to an existing file.

This is not valid for UV tables, neither for FITS output format.

The Buffer name must be specified (\* is not valid here).

#### 18.43.4 WRITE /REPLACE

```
[CLEAN\]WRITE Buffer File /REPLACE [/RANGE Start End Kind]
```

The selected channels are replaced in an existing file.

This is not valid for UV tables, neither for FITS output format.

The Buffer name must be specified (\* is not valid here).

#### 18.43.5 **WRITE /TRIM**

[CLEAN\]WRITE UV File /TRIM [ANY]

Remove the flagged visibilities while writing. A visibility is declared "flagged" if all channels in it are flagged, unless the keyword ANY is present. In this later case, if a single channel is flagged, the whole visibility is declared flagged.

## 19 CALIBRATE Language Internal Help

### 19.1 Language

APPLY	: Apply gain solution to current UV Data
COLLECT	: Gather several self-calibration solution together
DERIVE	: Derive Baseline gains from Antenna gains
SCALE_FLUX	: Adjust flux scale on a daily basis
MODEL	: Compute a UV model from the Clean Components Table
SOLVE	: Solve for complex gains using the UV model
TRANSFORM	: Apply transformation on frequency axis
UV_SELECT	: Select UV data to be displayed, imaged or written
UV_SELF	: Build the Self Calibration UV Table and dirty image
UV_SORT	: Sort and Transpose UV data for plotting

### 19.2 APPLY

```
[CALIBRATE\]APPLY [AMPLI|DELAY|PHASE [Gain]] [/FLAG [Threshold]]
```

Apply gain solution computed by MODEL and SOLVE (which are called implicitly by SELFCAL) or obtained by READ CGAINS to the current UV data. The optional arguments indicate whether this should be an AMPLITUDE, DELAY or PHASE gain, and what Gain value is used (in range 0 to 1). A DELAY gain is derived from a Phase self-calibration assuming the Phase errors represent pathlength changes (i.e. delays): phase solution is scaled with the Frequency ratio of the self-calibration and UV data to be calibrated.

If no argument is given, the current SELF\_MODE (see HELP SELFCAL) is used, and the gain is 1.0.

The /FLAG option controls whether data without a valid gain solution are kept unchanged or flagged. You can actually flag data on this basis even without applying the self-calibration solution.

#### 19.2.1 APPLY AMPLI

```
[CALIBRATE\]APPLY AMPLI [Gain] [/FLAG [Threshold]]
```

Apply an Amplitude gain calibration result. In doing so, the weights are never up-scaled, even when the Amplitude correction factor is smaller than 1. They are down-scaled for visibilities with correction factor larger than 1. The rationale behind this behaviour is to avoid giving more weights to data which has been modified in a self-calibration process.

### 19.2.2 APPLY DELAY

```
[CALIBRATE\]APPLY DELAY [Gain] [/FLAG [Threshold]]
```

Apply an PathLength (geometric delay) gain calibration result. The phases are assumed to scale strictly as the frequency. This mode is in general the most appropriate, since most residual phase errors are due to the atmospheric pathlength change.

However, it may produce spurious phase jumps if some instrumental phase had remained uncalibrated.

### 19.2.3 APPLY PHASE

```
[CALIBRATE\]APPLY PHASE [Gain] [/FLAG [Threshold]]
```

Apply a Phase gain calibration result. Any possible frequency dependence of the correction is neglected.

### 19.2.4 APPLY /FLAG

```
[CALIBRATE\]APPLY [AMPLI|DELAY|PHASE [Gain]] /FLAG [Threshold]
```

Apply gain solution (in AMPLITUDE, DELAY or PHASE) and flag data without a corresponding valid gain solution.

If the Threshold argument is present, all data with a correction exceeding that threshold are also flagged. This can be useful to filter out antennas that have unstable gains. A threshold of 90 degrees in phase, or 1.3 in amplitude may be appropriate.

The optional Gain argument has no effect on the Threshold: it is always the gain value in the CGAINS array that is compared to the Threshold.

USEFUL TRICK: If you forgot to flag the data while applying the self-calibration gain solution, you can still do it a posteriori without changing the amplitude and/or phase by using command

```
APPLY MODE 0 /FLAG Threshold
```

where MODE is any of AMPLI, DELAY or PHASE.

## 19.3 COLLECT

```
[CALIBRATE\]COLLECT FileFilter MergedFile [ReferenceAntenna] [/FLAG Threshold]
```



Average self-calibration solutions computed from different frequencies into a single one,.

FileFilter is a character string handling a filter to define all files storing the selected antenna gain solutions (files specified by SELF\_SNAME in the SELFCAL command).

MergedFile is the SNR weighted average of all selected self-calibration solutions. The averaging of phases is made in DELAY mode, i.e. assuming the self-calibration phases are actually Pathlengths (Delays) at the calibration frequency.

The reference antenna can optionally be changed for simpler display in this process if argument ReferenceAntenna is present.

### 19.3.1 COLLECT /FLAG

[CALIBRATE\]COLLECT FileFilter MergedFile [ReferenceAntenna] /FLAG Threshold

If more than 1 self-calibration loop is present in the selected files, the unstable solutions, defined as those for which the phase difference between the last 2 iterations exceeds Threshold sigma, are flagged.

Note that this option can be used to flag solutions even if only one frequency was used (i.e. when FileFilter refers to only one file).

## 19.4 DERIVE

[CALIBRATE\]DERIVE AgainsFile [CgainsFile]

Derive Baseline-based (Cgains) solution from an Antenna gain solution file. The Baseline-based solution is stored in buffer CGAINS, unless a file name is given by argument CgainsFile.

### 19.4.1 DERIVE Example

Commands COLLECT and DERIVE are typically used to improve wide-bandwidth self-calibration solutions. At NOEMA, a self-calibration solution can be computed independently for each of the 4 Wide band UV table. Assume these are stored in Wide-'i'-phase-sol.gdf, with i varying from 1 to 4.

```
COLLECT Wide-phase*.gdf Cont-sol.gdf
DERIVE Cont-sol.gdf Cont-cgains.uvt
READ CGAINS Cont-cgains.uvt
FOR I 1 to 4
```

```

    READ UV Wide-'i'.uvt
    APPLY DELAY /FLAG
    WRITE UV Self-Wide-'i'.uvt
NEXT

```

will average the (antenna-based) Phase calibration solutions (COLLECT) and compute the corresponding Baseline-based gains (DERIVE). The loop then applies this better self-calibration solution to each UV table, scaling the Phases according to Frequency.

## 19.5 SCALE\_FLUX

[CALIBRATE\]SCALE\_FLUX Find|Apply|List|Calibrate [Args...]

A set of commands to check flux calibration on a day to day basis. It gives the ratio between the observed flux (in the current UV data set) and the model flux for each separate period. The Model flux can be derived from Clean Component Tables using the MODEL command, or read from an outer file using READ MODEL.

Error bars are approximate. The User-defined command SOLVE\_FLUX performs a more accurate evaluation of the error, but is typically 50 times slower.

SCALE\_FLUX FIND [DateTolerance [UVmin UVmax]]  
determines, by linear regression, the best scaling factor to match date by date the UV data set with the MODEL data set. Separate Periods are defined when Dates differ more than DateTolerance (default 1 day). Only data with baseline lengths in the range UVmin UVmax are considered for the regression (default all).

SCALE\_FLUX APPLY VarName  
apply previously determined flux scale factors to the MODEL data set, previously read by READ MODEL. This is in general used only in an iterative search way, e.g. by the user-defined command SOLVE\_FLUX (which calls procedure solve\_flux). The resulting UV data set is loaded into the specified VarName SIC variable.

SCALE\_FLUX LIST  
print out dates, baselines and determined flux factors

SCALE\_FLUX CALIBRATE  
apply previously determined flux scale factors to the current UV data set (i.e. divide the visibilities by the scaling factor of each date, and correct the weight accordingly). This may then be written using command WRITE UV .

SCALE\_FLUX SOLVE [DateTolerance [UVmin UVmax]]  
 combines FIND and PRINT behaviours.

## 19.6 MODEL

```
[CALIBRATE\]MODEL [Arg1 [... ArgN] [/MINVAL Value [Unit]]
[/MODE CCT|IMAGE|UV_FIT [Frequency]]
```

This command creates model visibilities from Clean components, Clean images or UV\_FIT results from the last UV\_FIT command, depending on the /MODE option. If the option is not present, the default mode is CCT or UV\_FIT, depending whether CLEAN (or its specialized versions HOGBOM, CLARK, etc...) or UV\_FIT was done last.

The current UV data is used to define the visibility sampling and data weights. It should have only one channel, or the same number of channels as the specified model.

The resulting UV data is available in SIC structure UV\_MODEL. It can be written using WRITE UV\_MODEL, or selected for further use using command UV\_SELECT. MODEL and UV\_RESIDUAL are complementary commands ( $UV\_DATA = UV\_MODEL + UV\_RESIDUAL$ ).

For the Clean component the syntax is

```
[CALIBRATE\]MODEL [MaxIter] [/MINVAL Value [Unit]] [/MODE CCT [Frequency]]
```

It computes visibilities on the current UV sampling using a source model made of the MaxIter first Clean Components, or of all pixel values above the given Value if /MINVAL is present.

For the Clean image, the syntax is

```
[CALIBRATE\]MODEL [ImageName] [/MINVAL Value [Unit]] [/MODE IMAGE]
(ImageName is currently dummy. It will be used to specify any available
3-D Image variable later.)
```

For the UV\_FIT results, the syntax is

```
[CALIBRATE\]MODEL [F1 .. Fn] [/MODE UV_FIT]
which computes a model using the F1, ..., Fn fitted functions (default
all) for the current UV sampling.
```

UV\_MODEL can also be selected by using command UV\_SELECT for further imaging by UV\_MAP (and thus UV\_RESTORE) or display by SHOW UV.

### 19.6.1 MODEL /MINVAL

```
[CALIBRATE\]MODEL [MaxIter] /MINVAL Value [/MODE CCT [Frequency]]
```

For the CCT mode, construct the source model using all Clean Components until MaxIter (all if MaxIter is 0 or not specified). These components are stacked on a grid, and then all pixels above the given Value are taken as source model to derive visibilities.

```
[CALIBRATE\]MODEL [ImageName] /MINVAL Value [Unit] /MODE IMAGE [Frequency]
```

For the IMAGE mode, all pixels above the given Value are taken as source model to derive visibilities. An outer band of 1/8th of the image size is also set to 0 at map edges to avoid aliasing issues. Unit can be Jy, mJy, K or sigma. The default value is Jy.

The /MINVAL option is not valid in UV\_FIT mode.

### 19.6.2 MODEL /MODE

```
[CALIBRATE\]MODEL [Arg] [/MINVAL Value [Unit]] /MODE CCT|IMAGE|UV_FIT [Frequency]
```

Specify which input data is used to compute the model visibilities: Clean Component Table (CCT), Clean image (IMAGE) or UV\_FIT results.

By default, the UV\_MODEL output UV data takes its Frequency from the input Image or CCT data set. However, this can be superseded by the optional argument Frequency, which can take the value IMAGE (the default), UV or any frequency in MHz.

If not specified, the MODE is derived from the last executed operation (CLEAN or UV\_FIT)

## 19.7 SOLVE

```
[CALIBRATE\]SOLVE Time SNR [Reference]
/MODE [Phase|Amplitude] [Antenna|Baseline] [Flag|Keep]
```

Solve the baseline or antenna based gains using the current UV data and current MODEL.

Time is the integration time for the solution. SNR is the minimum Signal to Noise Ratio required to find a solution.

### 19.7.1 SOLVE /MODE

```
[CALIBRATE\]SOLVE Time SNR [Reference]
/MODE [Phase|Amplitude] [Antenna|Baseline] [Flag|Keep]
```

Depending on the /MODE arguments, the gains can be antenna-based or baseline-based, and include Phase or Amplitude, and data without solutions either KEEPEd or FLAGged,

## 19.8 TRANSFORM

[CALIBRATE\]TRANSFORM Operation FileIn FileOut [Control]

Apply a transformation along the Frequency axis of a data cube. Currently recognized Operation values are

FFT      Compute the (complex, hermitian) Fourier Transform  
WAVE      Compute a Wavelet Transform

FileIn is an Input data cube or the result of a previous transformation operation.

FileOut is the transformation result. The transformation is reversible:

TRANSFORM Oper In Out [ControlIn] followed by

TRANSFORM Oper Out In [ControlOut]

re-creates the In file provided the adequate Control[s] are properly specified.

Input Data Cubes can be in LMV (Position, Position, Velocity) or VLM format.

Output Files have a format that depends on the Operation. See HELP TRANSFORM FFT and HELP TRANSFORM WAVE for details.

### 19.8.1 TRANSFORM FFT

[CALIBRATE\]TRANSFORM FFT FileIn FileOut [Nchan]

Compute the Fourier Transform of FileIn along the Frequency/Velocity axis. The direction of the Fourier Transform depends on the nature of FileIn.

If FileIn is a standard Data Cube, a direct Fourier transform is performed, that leads to 4-D cube as FileOut, in order (position, position, complex, velocity). Its 3rd axis has 2 pixels that contain the Real and Imaginary parts. The number of channels is extended to the nearest integer of the form  $2^n 3^p 5^q$  where p and q are less or equal to 2.

Conversely, if FileIn is such a 4-D cube, an inverse Fourier transform is performed, leading to a (position, position, velocity) cube as FileOut.

Optionally, Nchan can specify how many channels are actually retained in this case.

### 19.8.2 TRANSFORM WAVE

```
[CALIBRATE\]TRANSFORM WAVE FileIn FileOut Direction
```

Compute a Wavelet Transform of FileIn along the Frequency/Velocity axis. Direction indicates if a direct or inverse Wavelet transformation is applied.

If Direction = 0, the number of channels is extended to the nearest power of 2, and a direct wavelet transform is performed

If Direction > 0, an inverse wavelet transform is performed (that assumes a power of 2 in number of channels in FileIn) and the first Direction channels only are kept in FileOut.

Thus, for a data cube of Nc channels, TRANSFORM WAVE In Out 0 followed by TRANSFORM WAVE Out In Nc re-creates the original data.

## 19.9 UV\_SELF

```
[CALIBRATE\]UV_SELF [CenterX CenterY UNIT [Angle]]  
[/RANGE [Min Max Type]] [/RESTORE]
```

Use (and if specified and/or needed create) the "Self Calibrated" UV dataset to make a dirty image, instead of using the current UV table.

UV\_SELF utilizes UV\_MAP for imaging. See HELP UV\_MAP for parameters.

### 19.9.1 UV\_SELF /RANGE

```
[CALIBRATE\]UV_SELF [CenterX CenterY UNIT [Angle]] /RANGE [Min Max  
Type]
```

Create and image the "Self Calibrated" UV data.

The "Self Calibrated" UV dataset is created from the current UV data set by extracting the range of channels specified by the /RANGE arguments Min Max Type. Type can be CHANNEL, VELOCITY or FREQUENCY. If /RANGE has no argument, all channels are averaged together.

It is then updated by command SOLVE at each self-calibration loop. See

SOLVE and ADVANCE\SELF CAL for details.

### 19.9.2 UV\_SELF /RESTORE

[CALIBRATE\]UV\_SELF /RESTORE

As UV\_RESTORE but for the self-calibrated UV table.

Restores the Clean image from the Clean Component Table by removing the components from the Self-calibrated UV data and imaging the residuals before adding them to the convolved Clean components.

See UV\_RESTORE for details.

### 19.10 UV\_SELECT

[CALIBRATE\]UV\_SELECT [Key]

Select which UV data set will be used by commands UV\_MAP, UV\_RESTORE, SHOW UV or WRITE UV. Key can be any of following:

DATA or UV_DATA	to specify the UV data obtained by READ UV
MODEL or UV_MODEL	to specify the UV data obtained by READ MODEL, or computed by command MODEL
RESIDUAL or UV_RESIDUAL	to specify the UV data computed by command UV_FIT

No other UV related command is affected by UV\_SELECT. They all work on the UV\_DATA dataset.

### 19.11 UV\_SORT

[CALIBRATE\]UV\_SORT Key [/FILE FileIn FileOut]

Sort and transpose the UV data set. The command has two different behaviours, depending on the /FILE option.

Without /FILE, the command works on the current UV data, loaded by command READ UV File, and creates a transposed, ordered copy of the UV data. The Key can be TIME for Time-Baseline ordering, BASE for Baseline-Time ordering. The sorted UV data is then available in variable UVS for further plotting. This is only done in an internal buffer. WRITE UV will **\*\*NOT\*\*** write this sorted, transposed, buffer.

With the /FILE option, the command creates in FileOut a sorted (but not transposed) copy of the UV data file specified in FileIn.

### 19.11.1 UV\_SORT /FILE

[CALIBRATE\]UV\_SORT Key /FILE FileIn FileOut

Creates in Fileout a sorted copy of the UV data found in FileIn. Key can be The Key can be TIME for Time-Baseline ordering, BASE for Baseline-Time ordering, or FIELDS for Mosaics. TIME ordering is required for efficient operation of the time averaging command UV\_TIME.

The command compares the file size to the available RAM memory (more specifically the size indicated by the logical name SPACE\_GILDAS) to decide whether the operation can be done in Memory only or needs intermediate files to perform the sorting.



## 20 ADVANCED Language Internal Help

### 20.1 Language

```

FEATHER      : Add short spacings (image feathering)
FLUX          : Compute integrated flux from Support or Mask
HOW_TO       : Getting help on how to perform some action
MAP_CONTINUUM : Determine the continuum image from a spectral cube
MAP_POLAR     : Derive Polarization Images from Stokes Images
MASK          : Define the MASK
MFS           : Multi Frequency Synthesis (under development - not functiona
MOMENTS       : Compute Moments for data cubes
PROPER_MOTION : Apply proper motion information to UV data
EXTSTOKES     : Extract one Stokes parameter from multi-polarization UV t
UV_ADD        : Add some extra column to the current UV data
UV_CIRCLE     : Deproject and compute radial visibility profile
UV_CORRELATE  : Spectral matching for UV data
UV_DEPROJECT  : Deproject UV data
UV_FIT        : Fit UV data with simple functions
UV_MERGE      : Merge (possibly many) UV tables
UV_MOSAIC     : Split or Build a Mosaic UV table
UV_PREVIEW    : Quick look at the spectral aspects of the UV data
UV_RADIAL     : Deproject and compute azimuthal average of UV data
UV_SHORT      : Compute and add short spacings to UV data
XY_SHORT      : Compute the short spacing image from the SINGLE Dish table

```

### 20.2 FEATHER

```
[ADVANCED\]FEATHER [?] [/FILE Combined HIGHRes LOWres] [/REPROJECT]
```

Combines a data cube containing High resolution data (HIGHres) with one containing the short spacing data (LOWres). Automatic reprojection and spatial resampling of the LOWres data may be done if the option /REPROJECT is specified.

The method is to hybridize in the UV plane the data, retaining short UV spacings from LOWres and long UV spacings from HIGHres. It is controlled mainly by variable FEATHER\_RADIUS, the transition radius. Other variables allow some fine tuning.

FEATHER ? will list the input parameters

### 20.2.1 FEATHER /REPROJECT

[ADVANCED\]FEATHER [/FILE Combined HIGHres LOWres] /REPROJECT

Allow to automatic reproject and rescale the LOWres images to the projection and sampling of the HIGHres one. If /REPROJECT is not present and the HIGHres and LOWres data do not match, FEATHER will complain and stop.

### 20.2.2 FEATHER /FILE

[ADVANCED\]FEATHER /FILE Combined HIGHres LOWres [/REPROJECT]

Takes the data from files named HIGHres and LOWres and put the combined result in file named Combined. The default extension .lmv-sky.

Without the /FILE option, FEATHER takes HIGHres from the SKY buffer, LOWres from the Short Spacing buffer (SHORT, equal to SINGLE if it is a data cube, or derived by UV\_SHORT if not), and put the result into an image variable named FEATHERED. The result can be written as any image by WRITE FEATHERED FileName.

Note: Currently, in all cases, the images reside in memory. A buffer mode for the /FILE option will be added later.

### 20.2.3 FEATHER Algorithm

FEATHER use the following steps

- Make oversampled Fourier Transform of both HIGHres and LOWres images
- Compute the truncation function  $f(r)$
- Make the Truncated compact Fourier Transform,  $f(r) \times T(\text{LOW})$
- Make the complement long baseline Fourier Transform,  $(1-f(r)) \times T(\text{HIGH})$
- Sum them  $T(\text{ALL}) = R \times f(r) \times T(\text{LOW}) + (1-f(r)) \times T(\text{HIGH})$   
     where  $R$  is taken from FEATHER\_RATIO
- Make the inverse Fourier Transform
- Truncate the resulting image to original size and Mask of the HIGHres images

If LOWres is a single-dish image,  $f(r)$  should normally be the beam of that telescope to use optimal Signal-to-noise ratio from that data set. However, because of pointing errors and other calibration issues such as spectral baseline, using a sharper transition function gives better results. FEATHER uses a  $\exp(-(r/\text{Radius})^{\text{Expo}})$  function, where Radius is taken from FEATHER\_RADIUS and Expo from FEATHER\_EXPO.

#### 20.2.4 FEATHER Variables:

FEATHER uses the following input variables  
FEATHER\_RADIUS, the transition radius  
FEATHER\_EXPO, an exponent controlling the transition sharpness  
FEATHER\_RATIO, a scale factor for the short spacing (LOWres) data.  
FEATHER\_RANGE, the limits of the overlapping region (see details)

#### 20.2.5 FEATHER\_RADIUS

Real FEATHER\_RADIUS (default 15.0)

FEATHER\_RADIUS is the transition radius (in meters) used to compute the combination function  $f(uv) = \exp(-(uv/\text{Radius})^{\text{Expo}})$ .

#### 20.2.6 FEATHER\_EXPO

Real FEATHER\_EXPO (default 8.0)

FEATHER\_EXPO is the exponent used to compute the combination function  $f(uv) = \exp(-(uv/\text{Radius})^{\text{Expo}})$ .

#### 20.2.7 FEATHER\_RATIO

Real FEATHER\_RATIO (default 1.0)

FEATHER\_RATIO is the scale factor to be applied to the LOWres data in the combination.

#### 20.2.8 FEATHER\_RANGE

Real FEATHER\_RANGE[2]

FEATHER\_RANGE[2] defines a region of "overlapping" UV spacings over which the ratio of LOWres and HIGHres visibilities can be checked. If the flux scale is correct, this ratio should be 1. FEATHER\_RANGE defaults to FEATHER\_RADIUS/1.15 and FEATHER\_RADIUS\*1.15.

The computed ratio is only a guide, and not used in the algorithm. A proper definition of FEATHER\_RANGE requires knowledge of the initial UV coverage of the HIGHres and LOWres data sets. If FEATHER\_RANGE is too large, the computed ratio has no real meaning.

## 20.3 FLUX

[ADVANCED\]FLUX Cursor|Mask|Support

Compute the integrated flux from the CLEAN image, using zones defined either by calling the Cursor, or by the current Support, or by the current Mask.

If the CLEAN data is a 3-D cube, the integrated flux will be a spectrum.

For FLUX MASK, if the Mask defines several separate zones, an integrated flux will be computed for each zone. Zones are ordered by decreasing number of pixels.

The FLUX results are available in the FLUX SIC structure, and can be displayed by SHOW FLUX and also SHOW COMPOSITE.

### 20.3.1 FLUX Limitations

FLUX MASK does not yet recognize properly Frequency dependent Masks.

### 20.3.2 FLUX Results

The FLUX results are available in the FLUX SIC structure

FLUX%NC	Number of channels
FLUX%FREQUENCIES[Flux%Nc]	Frequencies of the Channels
FLUX%VELOCITIES[Flux%Nc]	Velocities of the Channels
FLUX%NF	Number of Fields (Zones)
FLUX%VALUES[Flux%Nc,Flux%Nf]	Integrated Flux for each channel and Zone

For Cursor or Support defined regions, the enclosing polygon is also accessible:

FLUX%NX	Number of polygon summits
FLUX%X	X coordinates of summits
FLUX%Y	Y coordinates of summits

## 20.4 HOW\_TO

[ADVANCED\]HOW\_TO solve a simple problem

Ask IMAGER informations to help you solving your problem, expressed in a natural way. Examples

HOW do i subtract continuum ?

HOW do i control the display ?

Rules:

- simple words ("do" "i" "?" "the", etc...) are ignored. You can just type them to have a normal syntax in your question.
- all significant words (e.g. "subtract" and "continuum") must be found to have a matching topic.
- significant words use exact matching. "continuum" is not the same as "cont".
- partial match is possible if a significant word ends up by \*. "cont\*" will match "continuum".
- if no topic matches all significant words, a list of partial matches is given to guide you. Use a simpler question with less significant words among those proposed.

HOW\_TO ?

will list all topics

## 20.5 MAP\_CONTINUUM

[ADVANCED\]MAP\_CONTINUUM [DIRTY|CLEAN|Other] [/METHOD KEY [Parameters [...]]]

Compute a continuum image from the Clean, Dirty or Other 3-D data set. The derivation of the continuum follows the algorithm specified in the /METHOD option (or the last specified in this way if the /METHOD option is not present).

### 20.5.1 MAP\_CONTINUUM /METHOD

[ADVANCED\]MAP\_CONTINUUM [DIRTY|CLEAN|Other] /METHOD KEY [Parameters [...]]

Change the algorithm used to compute the Continuum image. KEY is the name of the selected method. Available methods are GLOBAL, GAUSS, SCM, C-SCM, and EGM. The fastest method is GLOBAL, than GAUSS, than SCM.

The selected method is sticky: it will be used until further modified by the /METHOD option.

### 20.5.2 MAP\_CONTINUUM GLOBAL

[ADVANCED\]MAP\_CONTINUUM [DIRTY|CLEAN|Other] /METHOD GLOBAL [Threshold [Nhisto]]

Compute the integrated spectrum (over the region specified by CENTER and SIZE variables), and delineate the line-free region by Gaussian fit-

ting the histogram of the spectrum intensity.

The optional arguments control the algorithm. Threshold is clipping level in sigma units: values in range 2.5 - 5 are usable (default 3.5). Nhisto is the number of histogram bins. The default is to adjust this number depending on the number of channels in the data. This is the same algorithm as used in UV\_CONTINUUM, or in a per pixel mode by the GAUSS method.

The continuum is then derived by integrating in the line-free regions. This method is fast, and gives a uniform noise since the same channels are used for all pixels. It may be inaccurate into several ways:

- Regions with strong broad line may still be contaminated by emission from the line wings
- The same applies to regions with line confusion.
- Continuum emission in regions with no line emission is not derived to the maximum sensitivity. This can be an issue in case of line confusion at some positions.

### 20.5.3 MAP\_CONTINUUM GAUSS

```
[ADVANCED\]MAP_CONTINUUM [DIRTY|CLEAN|Other] /METHOD GAUSS [Threshold [Nhist]]
```

Compute the continuum based on the per-pixel spectrum. Each spectrum is sigma-clipped and the histogram of the intensity distribution is fitted by a Gaussian. Corrective techniques are applied to ensure the fit has converged. The position of this Gaussian gives the continuum level. A noise estimate is also derived.

The method does not deliver a spatially independent noise, but adapts the bandwidth to the line free zones for each pixel. It may fail for pixels with are close to line confusion.

The optional arguments control the algorithm. Threshold is clipping level value for the Gaussian: values in range 2.5 - 4 are usable (default 3.5). Nhist is the number of histogram bins. The default is to adjust this number depending on the number of channels in the data.

### 20.5.4 MAP\_CONTINUUM SCM

```
[ADVANCED\]MAP_CONTINUUM [DIRTY|CLEAN|Other] /METHOD SCM [Threshold [MaxIter]]
```

Compute the continuum based on the per-pixel spectrum. Each spectrum

is sigma-clipped until convergence of the noise. The method is similar to the GAUSS method, but more robust at the expense of lower speed because of the iterative median clipping. Threshold is the number of sigma used for clipping. MaxIter is the maximum number of clipping operations performed (default 6).

The method does not deliver a spatially independent noise, but adapts the bandwidth to the line free zones for each pixel. It may fail for pixels with are close to line confusion, though less than the GAUSS method.

### 20.5.5 MAP\_CONTINUUM C-SCM

```
[ADVANCED\]MAP_CONTINUUM [DIRTY|CLEAN|Other] /METHOD C-SCM [Threshold [MaxIter]]
```

As for the SCM method, but the continuum is noise de-biased depending on the fraction of the bandwidth covered by emission and absorption lines. Marginally slower than SCM.

### 20.5.6 MAP\_CONTINUUM EGM

```
[ADVANCED\]MAP_CONTINUUM [DIRTY|CLEAN|Other] /METHOD EGM [Threshold]
```

This method is similar to the GAUSS method, but uses an exponentially modified Gaussian to fit the intensity distribution histogram.

## 20.6 MAP\_POLAR

```
[ADVANCED\]MAP_POLAR [GenericBegin [GenericEnd]] [/COMPUTE [Threshold]] [/BACKGROUND Type Min Max] [/STEP Step Xfirst Yfirst]
```

Derive or Display the Polarization fraction and Polarization angles images from the (I,Q,U) Stokes images.

GenericBegin indicates the file name prefix, and GenericEnd the filename postfix, including extension. The Stokes I (resp. Q, U) image is assumed to be in 'GenericName'-'I'-'GenericEnd' (resp. -Q and -U). The Polarization fraction image will be called 'GenericBegin'-'P'-'Type', while the Polarization angle image is 'GenericBegin'-'A'-'GenericEnd'.

The default end is ".lmv-clean". However, when using with the Imager PIPELINE, continuum images are in derived from the UV Table names by

adding +C before the file extension, so GenericEnd should be "+C.lmv-clean".

MAP\_POLAR ?

will simply display the current values of the "sticky" control parameters.

### 20.6.1 MAP\_POLAR /COMPUTE

```
[ADVANCED\]MAP_POLAR GenericBegin [GenericEnd] [/COMPUTE [Threshold]]
```

Compute the Polarization Fraction image 'GenericBegin' "-P"'.Type', and the Polarization Angle image 'GenericBegin' "-A" 'GenericEnd' from the 'GenericName' "-K" 'GenericEnd' images where -K is all of the -I, -Q, and -U Stokes images.

The derivation is only made on pixels that are brighter than Threshold sigma in the Stokes I image. The use of the /COMPUTE option reset all parameters that control further display to their default values.

### 20.6.2 MAP\_POLAR /BACKGROUND

```
[ADVANCED\]MAP_POLAR GenericBegin [GenericEnd] /BACKGROUND Type [Min Max] [/STEP Step Xfirst Yfirst]
```

Show the polarization vectors derived from the Polarization Angle and Fraction maps overlaid on a background image.

Type can be I for total intensity, F for fractional polarization in percent, or P for the polarized intensity. Min and Max indicate the SCALE to be used for the color scaling (through a temporary assignments of the SCALE values for SHOW command called by MAP\_POLAR).

Type, Min, and Max, like Step, Xfirst, Yfirst are "sticky" (remanent): they keep the previous value until a new one is specified, or are reset to their default values by use of the /COMPUTE option. Default is I for Type, 0 for Min and Max, which implies an automatic scaling to the data range.

### 20.6.3 MAP\_POLAR /STEP

```
[ADVANCED\]MAP_POLAR GenericBegin [GenericEnd] [/BACKGROUND Type Min Max] /STEP Step [Xfirst Yfirst]
```



Specify the Step in pixels between adjacent display of polarization vectors. If not specified, or if 0, Step is empirically derived from the angular resolution.

Xfirst and Yfirst indicate the starting pixel along the X and Y axis respectively, allowing a controlled centering of the vector distribution on the background image.

Type, Min, and Max, like Step, Xfirst, Yfirst are "sticky" (remanent): they keep the previous value until a new one is specified, or are reset to their default values by use of the /COMPUTE option. Default is 0 for Step, 1 for Xfirst and Yfirst.

## 20.7 MASK

[ADVANCED\]MASK [Key [Arguments ...]

Handle the MASK buffer, which can be used to select regions for Cleaning (see SUPPORT /MASK) or to mask any data cube.

Without argument (or with argument INTERACTIVE), an interactive tool is used to manipulate the mask. Valid operations are

ADD	Add a region to the mask
APPLY	Apply the mask to a buffer
CHECK	Check Clean and Mask consistency
INITIALIZE	Initialize the Mask (2D or 3D)
INTERACTIVE	Interactively define mask planes Step by Step
OVERLAY	Overlay the Mask to the Clean image
READ	Read the Mask from a file
REMOVE	Remove a region from the mask
SHOW	Show the Mask (as SHOW MASK)
THRESHOLD	Compute an automatic mask
USE	Use the Mask in Clean (as SUPPORT /MASK)
WRITE	Write the Mask on file (as WRITE MASK)

### 20.7.1 MASK Tricks

The MASK variable is ReadOnly. Yet, the user may want to modify it directly by himself. The following commands

```
DEFINE ALIAS WMASK MASK /GLOBAL
LET WMASK /STATUS WRITE
```

will create an alias to MASK which can be written by the user at will. This method is actually used in the Interactive MASK tool.

### 20.7.2 MASK ADD

[ADVANCED\]MASK ADD Shape [Arguments ...]

Add the specified Shape to the current mask. Shape can be

CIRCLE       Ox Oy Diameter

ELLIPSE      Ox Oy Major Minor Angle

RECTANGLE   Ox Oy Major Minor Angle

POLYGON      File

where Ox Oy are the center of the shapes, Major and Minor the axes length (= side lengths for the Rectangle...) and Angle the Position Angle of the Major axis.

For the POLYGON, the cursor is called if no File argument is given; else the polygon is read from the specified File.

### 20.7.3 MASK APPLY

[ADVANCED\]MASK APPLY SicVariable

Apply the mask to the corresponding 3-D variable.

The space dimensions must coincide (pixel per pixel), but the spectral axes can differ. The command will select the appropriate Mask channel for each plane of the SicVariable. If the Mask is 2-D only, it will be applied to all planes.

### 20.7.4 MASK CHECK

[ADVANCED\]MASK CHECK [SicVariable]

Check the Mask consistency against the specified SicVariable. The default is against Clean.

### 20.7.5 MASK INITIALIZE

[ADVANCED\]MASK INITIALIZE 2D|3D

Initialize an empty 2-D or 3-D mask. For a 2-D mask, the interactive tool will use the mean image as a background for the definition.

### 20.7.6 MASK INTERACTIVE

[ADVANCED\]MASK INTERACTIVE [Nchan]

Enter the interactive tool, moving Nchan channels at each Next or Previous button. Default is 1.

```
[ADVANCED\]MASK  
is equivalent to  
[ADVANCED\]MASK INTERACTIVE 1
```

### 20.7.7 MASK OVERLAY

```
[ADVANCED\]MASK OVERLAY
```

Display a SHOW-like overlay of the Mask on top of the current image (default is Clean, normally). All SHOW parameters apply.

### 20.7.8 MASK READ

```
[ADVANCED\]MASK READ File.[msk]
```

Read the Mask from a Gildas data-cube.

### 20.7.9 MASK REMOVE

```
[ADVANCED\]MASK REMOVE Shape [Arguments ...]
```

Remove the specified Shape from the current Mask. Shape can be

```
CIRCLE      0x Oy Diameter  
ELLIPSE     0x Oy Major Minor Angle  
RECTANGLE   0x Oy Major Minor Angle  
POLYGON     File
```

where 0x Oy are the center of the shapes, Major and Minor the axes length (= side lengths for the Rectangle...) and Angle the Position Angle of the Major axis.

For the POLYGON, the cursor is called if no File argument is given; else the polygon is read from the specified File.

### 20.7.10 MASK SHOW

```
[ADVANCED\]MASK SHOW
```

Similar to SHOW MASK command, but using a spacing equal to 0.5 to illustrate the boundaries.

**20.7.11 MASK THRESHOLD**

[ADVANCED\]MASK THRESHOLD Value Unit [GUARD Guard] [SMOOTH Smooth Length]  
[REGIONS Nregion]

Define a Mask from thresholding the CLEAN image. If the CLEAN image is 3-D, the Mask will be 3-D.

The method involves a first thresholding, optionally followed by a smoothing and a second thresholding to extend the support. The mask is the logical OR of the Raw and Smooth masks.

The algorithm to define the mask is controlled by 5 parameters, 4 of which are optional and specified as values after their corresponding keyword. The arguments

Value Unit  
indicate the threshold and its unit under which the mask is set to 0. The unit can be %, SIGMA, NOISE, Jy, milliJy, microJy, K, milliK, microK, or NATIVE.

Value is not just a simple number: its interpretation depends on whether it has an explicit sigma (+ or -), in which case only values above or below are retained, of no sign at all, in which case comparisons are made on the absolute values.

The default is 6 sigma. The noise is taken from the computed Clean noise (clean%gil%rms) if defined, or from the theoretical noise (dirty%gil%noise) if not.

SMOOTH Smooth Length

Smooth

indicates the threshold under which the Smooth Mask is set to 0 after smoothing. There is no default. If keyword SMOOTH is not present, there is no smooth mask. This smoothed threshold is in the same units as the main one.

Length

is the size of the smoothing gaussian to derive the smooth mask from the initial mask (in arcsec). If set to \*, or not specified, it takes the default which is the Clean beam major axis.

GUARD Guard

Guard

indicates the size of the guard band at edges where the mask is set to zero, in units of image size. The default is 0.18, i.e. the mask can extend a little more than the inner quarter. This is to avoid the edges where sidelobes aliasing occurs.

**REGIONS Regions****Regions**

is the maximum number of separate regions retained in the mask. The regions are ordered by decreasing size, and only the first Regions ones are kept. Default is 0, which means keep all regions.

**20.7.12 MASK USE**

[ADVANCED\]MASK USE

Use the MASK in Clean deconvolution.

Equivalent to SUPPORT /MASK command.

**20.7.13 MASK WRITE**

[ADVANCED\]MASK WRITE File

Save the Mask on a File. Default extension is .msk.

Equivalent to WRITE MASK command.

**20.8 MFS**

[ADVANCED\]MFS

**\*\* NOT OPERATIONAL -- UNDER DEVELOPMENT \*\***

Multi-frequency synthesis, allowing to account for spectral index changes across the observed field of view for very wide bandwidths continuum imaging.

**20.9 MOMENTS**

[ADVANCED\]MOMENTS [/CUTS] [/MASK] [/METHOD Mean|Peak|Parabolic]  
[/RANGE Min Max TYPE] [/THRESHOLD Thre [Unit]]

Compute the 4 main "moments" of the CLEAN (or SKY) data cube, and return them as SIC Image variables. SKY has priority over CLEAN if both are defined.

The 4 moments are

M\_AREA Integrated area over the velocity range

M\_PEAK Peak brightness value

M\_VELO Mean or peak velocity

M\_WIDTH Weighted line width

The options control the method, the selected part of the cube (default channels from FIRST to LAST), and the threshold for detection (default 3 sigma).

The resulting images can be displayed using command SHOW MOMENTS and saved using WRITE MOMENTS.

### 20.9.1 MOMENTS /CUTS

```
[ADVANCED\]MOMENTS [/CUTS MinArea [NRegions]]
```

Restrict the moment images to the region(s) where the integrated area M\_AREA is greater than MinArea. This option is exclusive of any other.

The optional NRegions number is the maximum number of separate regions to be kept (default 1).

### 20.9.2 MOMENTS /MASK

```
[ADVANCED\]MOMENTS /MASK [/METHOD Mean|Peak|Parabolic]
[/RANGE Min Max TYPE] [/THRESHOLD Thre [Unit]]
```

Compute the 4 main moments and truncate them outside the current MASK.

### 20.9.3 MOMENTS /METHOD

```
[ADVANCED\]MOMENTS /METHOD Mean|Peak|Parabola [/MASK]
[/RANGE Min Max TYPE] [/THRESHOLD Thre [Unit]]
```

Specify which method to be used to compute the velocity and peak values. The default method, MEAN, computes an intensity weighted velocity, and takes the peak intensity at each pixel. Method PEAK takes the velocity at the peak intensity. Method PARABOLA makes a parabolic fit over 3 channels around the peak intensity channel to derive the velocity, and takes the peak value of this parabola for the peak brightness.

### 20.9.4 MOMENTS /RANGE

```
[ADVANCED\]MOMENTS /RANGE Min Max TYPE [/MASK]
[/METHOD Mean|Peak|Parabola] [/THRESHOLD Thre [Unit]]
```

Specify the range of channels to be selected. TYPE can be VELOCITY, FREQUENCY or CHANNELS. If not present, the range is defined by FIRST and

LAST variables.

### 20.9.5 MOMENTS /THRESHOLD

```
[ADVANCED\]MOMENTS /THRESHOLD Thre [UNIT] [/MASK]
[/METHOD Mean|Peak|Parabola] [/RANGE Min Max TYPE]
```

Specify the minimum intensity of the input data cube to consider a given pixel, channel as valid. Keyword UNIT can be given to indicate whether Thre is given in noise unit (UNIT = SIGMA) or in data cube units (UNIT = FLUX).

The default arguments of /THRESHOLD are 3 SIGMA.

## 20.10 PROPER\_MOTION

```
[ADVANCED\]PROPER_MOTION muRA muDec [/FILE FileIn FileOut]
```

Apply specified proper motion to current or specified UV Table. Proper motion values are specified in milliarcsec per year (mas/a).

If no /FILE option is present, they are applied to the current UV table.

### 20.10.1 PROPER\_MOTION /FILE

```
[ADVANCED\]PROPER_MOTION muRA muDec /FILE FileIn FileOut
```

Apply specified proper motion to the specified UV Tables. Proper motion values are specified in milliarcsec per year (mas/a).

Currently, the input file FileIn and output file FileOut must differ.

## 20.11 STOKES

```
[CLEAN\]STOKES Key [/FILE UVin UVout]
```

Derive a single polarization UV table with the polarization state specified by Key from a multi-polarization UV table. The command work on the UV buffer unless the /FILE option is present.

Key is any of the following: NONE, I, Q, U, V, RR, LL, HH, VV, XX, YY.

A typical use is after command FITS on CASA data:

```
FITS Fits.uvfits TO UVin.uvt
```

STOKES NONE /File UVin Uvout

### 20.11.1 STOKES /FILE

[CLEAN\]STOKES Key /FILE UVin UVout

Derive a single polarization UV table UVout with the polarization state specified by Key from a multi-polarization UV table UVin. Key is any of the following: NONE, I, Q, U, V, RR, LL, HH, VV, XX, YY.

## 20.12 UV\_ADD

[ADVANCED\]UV\_ADD ITEM [Mode] [/FILE FileIn FileOut]

Compute and add some missing information in a UV Table, such as the Doppler correction and the Parallaxtic Angle

The information is derived from the Observatory coordinates, from the Telescope name in the input UV table. This can be supplied by the SPECIFY TELESCOPE command if not available.

ITEM can take values DOPPLER, PARALLACTIC or \* for both.

Mode is a debug control integer which indicates in which column the information should be placed. The default is 0, i.e. the command will reuse the column of the appropriate type, or add it if not present. It may be set to 3, as often column 3 contains the Scan number, which is not a relevant information for imaging. Other values are at the user's peril...

### 20.12.1 UV\_ADD /FILE

[ADVANCED\]UV\_ADD ITEM [Mode] /FILE FileIn FileOut

Use the UV data in the file FileIn, and write the completed visibilities in the file FileOut.

## 20.13 UV\_CIRCLE

[ADVANCED\]UV\_CIRCLE [x0 y0 Rota Incl1]  
[/SAMPLING QSTEP [Unit [QMIN QMAX]]] [/ZERO [Flux]]

Compute a UV table containing the radial distribution of the azimuthal



average of the visibilities after deprojection for inclination and orientation (Incli, Rota, in Degrees) around a specified center (x0,y0 in Radians). All arguments default to 0. ROTA is here the position angle of axis of (assumed) rotational invariance of the object. Thus, when using results from UV\_FIT one should use ROTA = PA-90, where PA is the Position Angle of the Major axis.

The resulting UV table have visibilities only with V values equal to 0, so that the U values contain the radial distance in the UV plane. This is convenient to display the azimuthal average of the visibilities as a function of UV distance, but cannot be used for further imaging.

See UV\_RADIAL if you want to image the circular average of the brightness distribution.

### 20.13.1 UV\_CIRCLE /SAMPLING

```
[ADVANCED\]UV_CIRCLE [x0 y0 Rota Incli] /SAMPLING QSTEP [Unit [QMIN
QMAX]]
[/ZERO [Flux]]
```

Specify the sampling of the UV distances: Qstep is the step, Qmin and Qmax the min and max. Distances are in the specified unit, which can be "meter" (default) or "kwave". If /SAMPLING is not present, an automatic guess is made from the minimum and maximum baselines and the dish diameter.

### 20.13.2 UV\_CIRCLE /ZERO

```
[ADVANCED\]UV_CIRCLE [x0 y0 Rota Incli] /ZERO [Flux]
[/SAMPLING QSTEP [Unit [QMIN QMAX]]]
```

Add the zero spacing flux to the azimuthal average. If no value is given, the zero spacing flux is extrapolated from the shortest baselines using a parabolic interpolation centered on (u,v)=(0,0).

## 20.14 UV\_CORRELATE

```
[ADVANCED\]UV_CORRELATE ResultFile [/FILE Data Model]
```

Compute the Frequency Cross-Correlation spectrum of two UV data sets. The two UV data set must be referenced to the same position.

The data sets can be specified with the /FILE option. If not, UV\_CORRELATE will correlate the current UV data (UV\_DATA) with the Model UV data

(UV\_MODEL), that can be loaded by READ UV and READ MODEL respectively. The Model UV data can also be computed by command MODEL.

ResultFile indicates on which data file the result must be written. This result is a UV table with only the (0,0) spacing, that contains the correlation spectrum. It can be displayed using command UV\_PREVIEW.

See command BUNDLES\UV\_DETECT (that encapsulates in a more comprehensive way UV\_CORRELATE) to compute the same result from a UV data file and an Image model.

### 20.14.1 UV\_CORRELATE /FILE

[ADVANCED\]UV\_CORRELATE /FILE Data Model

Compute the Frequency Cross-Correlation spectrum of two UV data sets in the specified file names.

The two UV data set must be referenced to the same position, and have a compatible velocity resolution.

### 20.15 UV\_DEPROJECT

[ADVANCED\]UV\_DEPROJECT x0 y0 Rota Incl

Deproject a UV table for inclination and orientation (Incl, Rota, in Degrees) around a specified center (x0,y0 in Radians). This can be useful for almost planar or cylindrical objects (e.g. galaxies, or protoplanetary disks). When using results from UV\_FIT one should use ROTA = PA-90, where PA is the Position Angle of the Major axis for a proper deprojection.

The result becomes the current UV table.

### 20.16 UV\_FIT

[ADVANCED\]UV\_FIT [Func1 .. FuncN] [/QUIET] [/SAVE File] [/WIDGET N]

Fit UV data with a few simple functions. Func1 to FuncN (currently  $N < 5$ ) are the names of the functions to be fitted. If not specified, the last names (or those attributed by the /WIDGET options) are used.

The models are either simple functions or linear combinations of simple functions. The results of the fitting process are the position offsets in R.A. and Dec (in arc second) of the model source from the phase ref-

erence center, and its flux (Jansky). Depending on the fitting functions additional fit results are possible. Currently supported distributions and additional fit parameters are:

POINT	Point source	: None
E_GAUSS	Elliptic Gaussian source	: FWHM Axes (Major and Minor), Pos Ang
C_GAUSS	Circular Gaussian source	: FWHM Axis
C_DISK	Circular Disk	: Diameter
E_DISK	Elliptical (inclined) Disk	: Axis (Major and Minor), Pos Ang
RING	Annulus	: Diameter (Inner and Outer)
EXPO	Exponential brightness	: FWHM Axis
POWER-2	$B = 1/r^2$	: FWHM Axis
POWER-3	$B = 1/r^3$	: FWHM Axis
E_RING	Inclined Annulus	: Inner, Outer, Pos Ang, Ratio
E_EXPO	Elliptic exponential	: FWHM Axes (Major and Minor), Pos Ang
SPERGEL	Spergel brightness profile	: FWHM Axis, nu
E_SPERGEL	Elliptic Spergel profile	: FWHM Axes (Maj. and Min.), Pos Ang, n

The function parameters are found in a SIC structure named UVF% under names UVF%PARi%PAR[7] (starting values), UVF%PARi%RANGE[7] (starting ranges) and UVF%PARi%START[7] (number of starts). The /WIDGET option is a convenient way to set these variables.

UV\_RESIDUAL will compute the fit residual when used after UV\_FIT, while it computes the residual from the Clean component list if used after CLEAN.

WRITE UV\_FIT file[.uvfit] will save the fit results in a GILDAS table, in the same format than that of the UV\_FIT task.

The Pos Ang (PA) are the Position Angles of the major axis of the distribution. To deproject the elliptical shapes, one should use the Position Angle of the rotational axis, PA-90 (see commands UV\_CIRCLE, UV\_DEPROJECT and UV\_RADIAL)

### 20.16.1 UV\_FIT /QUIET

```
[ADVANCED\]UV_FIT /QUIET [/WIDGET N]
```

Activate the quiet mode. Only a progress report (25%, 50% and 75% done) is issued in this case, not a per-channel message. This mode is recommended for many channels.

### 20.16.2 UV\_FIT /SAVE

```
[ADVANCED\]UV_FIT /SAVE OutputFile
```

Save the input parameters, into a text output file. This file is then a script which can be re-executed to set the input parameters for UV\_FIT.

If the data has only 1 channel, the fit results (see HELP UV\_FIT Result-Values) are also written in the same file.

### 20.16.3 UV\_FIT /WIDGET

```
[ADVANCED\]UV_FIT /WIDGET N [/QUIET]
```

Create a Widget to specify the function names and input parameters for UV\_FIT for N functions. Once these are defined by the user, clicking the GO button will launch the computation.

### 20.16.4 UV\_FIT History

```
[ADVANCED\]UV_FIT [Func1 .. FuncN] [/QUIET] [/SAVE File] [/WIDGET N]
```

This command is similar to the pre-existing task UV\_FIT, but works on the current UV buffer, thus offering a simpler integration in IMAGER.

### 20.16.5 UV\_FIT ResultTable

The UV\_FIT results are stored in an internal table named UV\_FIT. This table can later be saved using command WRITE UV\_FIT FileName. The table is organized as a MxN matrix, where M is the number of channels in the UV data and the organization in N is the following:

```
N: P1 P2 P3 Vel A1 A2 A3 Par1 Err1 Par2 Err2 ... A1 A2 A3 Par1 Err1 ...
```

where P1 = RMS of the fitting process

P2 = number of supplied functions (NF\$)

P3 = total number of parameter

Vel = velocity of the i-th channel (i lies between 1 and M)

A1 = 1 (for the first function), = 2 (for the second function)

A2 = function code (POINT = 1, E\_GAUSS = 2, ... , POWER-3 = 8)

A3 = number of parameters of the function

Parx = result of the fit parameter (order of appearance in PARAMxx\$)

Errx = error of the fitting process for the parameter Parx

For example, fitting models with the two functions POINT and C\_GAUSS produce files with N=24.

SHOW UV\_FIT will display plots from this table.

### 20.16.6 UV\_FIT ResultValues

For data with only 1 channel, the fit UV\_FIT results are available as variables UVF%PARi%RESULTS[7] (for the results) and UVF%PARi%ERRORS[7] (for their formal errors) for every function number i. These variables are written in the output file by the UV\_FIT /SAVE OutputFile command.

They are also available in the internal table named UV\_FIT, as for any other number of channels (see HELP UV\_FIT ResultTable)

## 20.17 UV\_MERGE

```
[ADVANCED]\UV_MERGE OutFile /FILES In1 In2 ... Inn
[/MODE [LINE|STACK|CONCATENATE|CONTINUUM [Index [Frequency]]]
[/SCALES F1 ... Fn] [/WEIGHTS W1 ... Wn ]
```

Merge many UV data files, with calibration factor and weight factors and (for Line data) spectral resampling as in the first one. OutFile is the name of the output UV table.

For Line data, the default is to merge lines of the same molecular transition (same Rest Frequency). However the STACK mode allows stacking UV data from different spectral lines, re-aligned in velocity. This can allow detection of molecules with many transitions.

For Continuum data (1 channel and/or option /MODE CONTINUUM), a spectral index and a reference Frequency can be specified to merge all UV tables.

### 20.17.1 UV\_MERGE /FILES

```
[ADVANCED]\UV_MERGE OutFile /FILES In1 In2 ... Inn
[/MODE [LINE|STACK|CONCATENATE|CONTINUUM [Index [Frequency]]]
[/SCALES F1 ... Fn] [/WEIGHTS W1 ... Wn ]
```

Specify the names of the UV tables to be merged. The first one is used as a reference for resampling (line data) or Frequency (continuum data).

Instead of individual file names, a character array variable can be used to specify the input UV tables. A common use is with the DIR%FILE array created by command SIC FIND:

```
SIC FIND A-*.uvt
UV_MERGE M-all /FILES DIR%FILE
will merge in Line mode all files of name A-*.uvt into M-all.uvt
```

### 20.17.2 UV\_MERGE /MODE

```
[ADVANCED]\UV_MERGE OutFile /FILES In1 In2 ... Inn
/MODE [LINE|STACK|CONCATENATE|CONTINUUM [Index [Frequency]]]
[/SCALES F1 ... Fn] [/WEIGHTS W1 ... Wn ]
```

Specify the merging mode. The default mode is LINE.

In LINE mode, for spectral line UV tables (more than 1 channel), the default is that the spectral lines must have the same Rest Frequency. Resampling (in velocity, which is then identical in frequency) is done on the grid of the first UV table In1.

In mode CONCATENATE, a common spectral axis encompassing those of the initial UV tables is defined, and all UV tables are resampled on this one.

In mode STACK, the Rest Frequencies can differ. Resampling is then done in velocity, and the (u,v) coordinates scaled as the Rest Frequency ratios to conserve the angular resolution of the data. The /SCALES and /WEIGHT factors can be used to incorporate prior knowledge of the expected line ratios to optimize S/N.

For continuum UV tables (1 channel or option /MODE CONTINUUM), a spectral index can be specified, as well as a reference Frequency. (u,v) coordinates are scaled appropriately, as well as Flux and Weights in this case. The /SCALES and /WEIGHTS factors are applied on top of this automatic spectral index scaling. Input Line UV Tables are treated as multi-frequency Continuum ones (as in UV\_CONTINUUM command).

### 20.17.3 UV\_MERGE /SCALES

```
[ADVANCED]\UV_MERGE OutFile /FILES In1 In2 ... Inn
[/MODE [LINE|STACK|CONCATENATE|CONTINUUM [Index [Frequency]]]
/SCALES F1 ... Fn [/WEIGHTS W1 ... Wn ]
```

Specify the flux scaling factors for each UV table.

For /MODE CONTINUUM, the spectral index is applied separately from this flux scale factor (by further multiplication).

### 20.17.4 UV\_MERGE /WEIGHTS

```
[ADVANCED]\UV_MERGE OutFile /FILES In1 In2 ... Inn
[/MODE [LINE|STACK|CONCATENATE|CONTINUUM [Index [Frequency]]]]
[/SCALES F1 ... Fn] /WEIGHTS W1 ... Wn
```

Specify the weight scaling factors for each UV table. The weight scaling factor is independent of the flux scaling factor. This means that to conserve the Signal-to-Noise ratio, one should normally use  $W_i = 1/F_i^2$ .

For /MODE CONTINUUM, the spectral index is applied separately from this weight scaling factor (by further multiplication).

## 20.18 UV\_MOSAIC

```
[ADVANCED]\UV_MOSAIC Mosaic MERGE|SPLIT [Fields [...]]
```

Built a Mosaic UV table from individual fields (MERGE keyword), or split a Mosaic UV table in individual fields (SPLIT keyword)

For MERGE, all single-field UV tables must match spectroscopically. Use command UV\_RESAMPLE /LIKE on individual fields if needed to ensure this.

### 20.18.1 UV\_MOSAIC MERGE

```
[ADVANCED]\UV_MOSAIC Mosaic MERGE Fields [...]
```

Build a new Mosaic UV table from the single-fields UV tables indicated by the arguments following the MERGE keyword.

The Mosaic UV table name will be Mosaic.uvt

If only 1 argument is following the keyword MERGE, it is assumed to be a SIC Character array variable containing the filenames of all single-field UV tables needed to build the mosaic. This is typically used as follows:

```
IMAGER> SIC FIND fields*.uvt
```

```
IMAGER> UV_MOSAIC my_mosaic MERGE dir%file
```

The number of fields is thus given by the size of the array.

If more than 1 argument follow the keyword MERGE, each one indicates a

separate single-field UV table. It is not possible to use a character array in this case.

### 20.18.2 UV\_MOSAIC SPLIT

[ADVANCED]\UV\_MOSAIC Mosaic SPLIT [Fields]

Split a UV table of name "Mosaic.uvt" into a series of single-fields UV tables of generic name Fields. Individual names are then Fields-1.uvt, ... Fields-n.uvt

If not specified, Fields default to the name given by Mosaic.

### 20.19 UV\_PREVIEW

[ADVANCED]\UVPREVIEW [TAPER Ntaper] [CLIP Threshold] [HISTO Nhisto]  
[SMOOTH Nsmooth] [/BROWSE [Ataper]] [/FILE UvData.uvt [Drop]]

A fast previewer to figure out if there is signal and what is its spectral shape. The command attempts to find out the line free regions and to estimate a continuum region.

The output of UV\_PREVIEW can be used for further processing commands (UV\_BASELINE and UV\_FILTER, UV\_SPLIT, SPECIFY, etc...)

If a catalog is defined (see HELP CATALOG), it will also display line identification (red for detected ones, blue for the others).

The behaviour is controlled by 4 parameters than can be set through the "KEY Value" optional argument pairs. These are

TAPER Ntaper : number of scale sizes (default 4)  
CLIP Threshold : Clipping level in Sigma (default 3.5)  
SMOOTH Nsmooth : Number of spectral smoothing (default 3)  
HISTO Nhisto : Size of histogram

These values are "sticky": they remain valid until further change, and they can be listed by

UV\_PREVIEW ?

#### 20.19.1 UV\_PREVIEW /BROWSE

[ADVANCED]\UV\_PREVIEW /BROWSE [Ataper] [/FILE FileIn] [Drop]]

Use a "split window" previewer instead of just one window. The bottom window displays full spectra for all tapers, the top window is a us-



er-controlled zoom of one of the tapers, with spectral line identifications if a catalog is available. The cursor is called and the user can adjust the zoom display with it. Press H for help, E for exit.

Ataper indicates the taper number (default: last one).

### 20.19.2 UV\_PREVIEW /FILE

```
[ADVANCED\]UV_PREVIEW [Key Value [...]] /FILE FileIn [Drop] [/BROWSE
Ataper]
```

Without /FILE, UV\_PREVIEW works from the current UV data set.

With the /FILE option, it will pre-view the UV data set from the specified file. Edge channels are automatically dropped in this mode, as many telescopes (NOEMA or ALMA) do not produce useable data in these ones. The default drop is 5% of bandwidth on each side, but can be changed with the option Drop value (in %).

### 20.19.3 UV\_PREVIEW Algorithm

UV\_PREVIEW computes for Ntapers different tapers the spectrum towards the phase center. The taper ranges are determined from the available baseline lengths and telescope diameter. Ntapes is controlled by the value of Key TAPER.

These spectra are then smoothed by averaging several channels (1,4,16 and 64) to be sensitive to different linewidths. The number of smoothed spectra per taper is controlled by the value of Key SMOOTH.

For each spectrum, UV\_PREVIEW then attempts to figure out if there is line emission and the line-free channels to define the continuum level. This is based on the histogram of the intensity distribution of all channels. The most likely value and the noise level is derived from this histogram. An iterative scheme, blanking out of range (presumably line emission) channels, is used for this to converge towards a Gaussian histogram, which normally represents the noise distribution around the continuum level.

As a last step, blanked channels are accumulated in a list of channels, which thus contain possible line emission at any of the Ntapers angular scales and Nsmooth spectral resolutions.

#### 20.19.4 UV\_PREVIEW Limitations

UV\_PREVIEW cannot identify lines if there are too few channels. It will only display the spectra in this case. A minimum of 32 channels is required, but confused spectra may also prevent a proper line recognition.

The line detection is based on the current specified velocity. If this is incorrect, lines may appear shifted and considered as not detected. PREVIEW%TOLERANCE indicates the matching precision in frequency (default is 2 MHz).

If variable \sicvar{REDSHIFT} exists, the frequency scale is corrected for that source Redshift, so that line identification remains possible.

#### 20.19.5 UV\_PREVIEW Output

UV\_PREVIEW returns the list of possible line channels through variable PREVIEW%CHANNELS. If no line emission was identified at any scale, the list is empty and the variable does not exist.

With this list, the user can compute the continuum image, using commands UV\_FILTER /CHANNELS PREVIEW%CHANNELS (or simply UV\_FILTER), then UV\_CONTINUUM and the usual UV\_MAP and CLEAN. Alternatively, the user can filter out the continuum emission using UV\_BASELINE.

If a catalog is present, UV\_PREVIEW also creates several other variables. PREVIEW%FOUND indicates the spectral line falling in the frequency range, while PREVIEW%DETECTED indicates the detected lines. These two structures have the following variables, e.g. for FOUND:

PREVIEW%Found%FREQ      The line frequencies

PREVIEW%Found%LINES      The line names

PREVIEW%Found%SPECIES    The molecule name

PREVIEW%EDGES and PREVIEW%FREQUENCIES contains the start and end channels (for %EDGES, resp. frequencies for %FREQUENCIES) of each contiguous range of channels in PREVIEW%CHANNELS. These variables are used for line identification and imaging in the

```
@ image_lines
script.
```

Finally, UV\_PREVIEW returns in PREVIEW%FMIN PREVIEW%FMAX the frequency coverage, and in PREVIEW%FREQ the rest frequency of the most likely spectral line in the window, and in PREVIEW%LINES its name. If no spectral line has been identified, PREVIEW%FREQ is just the mean of PREVIEW%FMIN and PREVIEW%FMAX, and PREVIEW%LINES does not exist.

## 20.20 UV\_RADIAL

```
[ADVANCED\]UV_RADIAL x0 y0 Rota InclI [/SAMPLING QSTEP [QMIN QMAX]]
[/ZERO [Flux]]
```

Compute a UV table containing the radial distribution of the azimuthal average of the visibilities after deprojection for inclination and orientation (InclI, Rota, in Degrees) around a specified center (x0,y0 in Radians). ROTA is here the position angle of axis of (assumed) rotational invariance of the object. Thus, when using results from UV\_FIT one should use ROTA = PA-90, where PA is the Position Angle of the Major axis.

The result becomes the current UV table. The resulting UV table has a (u,v) coverage which is extended by rotation, so that it can be used to image the (rotationally symmetric) 2-D radial distribution using standard commands like UV\_MAP and CLEAN. The radial profile of the brightness distribution can then be recovered by using any radial cut through this image.

Note, however, that in a SHOW UV command with "radius" along one axis, all visibilities at different azimuth are superimposed. See UV\_CIRCLE for a different way of computing an azimuthal average, more suited for SHOW UV.

### 20.20.1 UV\_RADIAL /SAMPLING

```
[ADVANCED\]UV_RADIAL [x0 y0 Rota InclI] /SAMPLING QSTEP [Unit [QMIN
QMAX]]
[/ZERO [Flux]]
```

Specify the sampling of the UV distances: Qstep is the step, Qmin and Qmax the min and max. Distances are in the specified unit, which can be "meter" (default) or "kwave". If /SAMPLING is not present, an automatic guess is made from the minimum and maximum baselines and the dish diameter.

### 20.20.2 UV\_RADIAL /ZERO

```
[ADVANCED\]UV_RADIAL [x0 y0 Rota InclI] /ZERO [Flux]
[/SAMPLING QSTEP [Unit [QMIN QMAX]]]
```

Add the zero spacing flux to the azimuthal average. If no value is given, the zero spacing flux is extrapolated from the shortest baselines using a parabolic interpolation centered on (u,v)=(0,0).

## 20.21 UV\_SHORT

[ADVANCED\]UV\_SHORT [Arg] [/CHECK] [/REMOVE]

(documentation for Version 3.9 of command UV\_SHORT)

Compute the Short Spacings from the current Single Dish dataset (read by READ SINGLE) and merge it to the current UV data. If the SINGLE dish data is a Class table, UV\_SHORT also creates the SHORT image variable, containing the 3-D data cube from which short spacings are computed.

UV\_SHORT takes sensible default guesses for most parameters. UV\_SHORT ? lists the essential parameter values, UV\_SHORT ?? some additional ones, and UV\_SHORT ??? even the debugging control variables.

The current values can be overridden by the user, who need to set (and if needed to define first) the corresponding SHORT\_whatever variable. SHORT\_SD\_FACTOR is the main one which may need to be specified by the user, as the Single Dish data is rarely in the appropriate unit.

The resulting UV table becomes the current UV data, and can be imaged, written, etc...

### 20.21.1 UV\_SHORT /CHECK

UV\_SHORT /CHECK

Verify the spectral compatibility between the "single" data set (obtained by READ SINGLE) and the UV data obtained by READ UV. The compatibility is returned in variable SHORT\_STATUS, which is set to YES if both data sets can be merged by UV\_SHORT.

### 20.21.2 UV\_SHORT /REMOVE

UV\_SHORT /REMOVE

Removes any short spacing from the current UV data set.

### 20.21.3 UV\_SHORT Algorithm

UV\_SHORT task computes pseudo-visibilitys for short or zero spacings from a single dish table of spectra (Class table) or LMV data cube. These pseudo visibilitys are appended to the current (presumably a Mosaic) UV table.

Short spacings are computed when the Interferometer dish diameter is smaller than the Single-dish diameter, Zero spacings otherwise (see HELP UV\_SHORT Zero\_Spacing for this case)

For short spacings, the command performs two steps

- (1) Creation of a "well behaved" map from the spectra.
- (2) Extraction of UV visibilitys from this map.

See HELP UV\_SHORT Step\_i for detailed explanations of the method steps.

With recent UV tables and Single Dish CLASS table, most parameters are automatically determined. The only parameter to be specified remains SHORT\_SD\_FACTOR (although that one may also be determined automatically if the input single dish data set is in main-beam brightness temperature).

A parameter set to 0 value indicates the appropriate default should be used.

#### 20.21.4 UV\_SHORT Zero\_Spacing

Zero spacings are computed when the single dish diameter is the same as the interferometer dish diameter. Zero spacing extraction proceeds differently for Class data tables and 3-D data cubes.

In the data cube case, the nearest pixel matching the direction of each field is taken as the Zero spacing for this field. If there is no point close enough, according to the specified position tolerance SHORT\_TOLE, an error occurs.

In the Class data table case, all spectra within the specified position tolerance of a field center are averaged together to produce the Zero spacing. If none is found, an error occurs.

#### 20.21.5 UV\_SHORT Step\_1

Step (1) Creation of a "well behaved" map from the spectra. This

map is made available to the user as the SHORT datacube, and can be saved by WRITE SHORT.

Step (1) only can be performed independently by command XY\_SHORT, to use the SHORT image in command FEATHER for example.

Step (1) only occurs if the input single-dish data set (read by READ SINGLE) is a table of spectra. The table format is described in the CLASS\GRID command of CLASS.

The identification of the input single-dish data set as a table of spectra is based on the Header.

It is recommended that this input table is a collection of single-dish, Nyquist sampled spectra covering twice the interferometric field of view of interest. However, UV\_SHORT does *\*NOT\** make any assumption. It thus tries to compute a "well behaved" map by linear operations (convolutions) from the original spectra, in an optimum way from signal to noise point of view. The map is extrapolated smoothly towards zero at the map edge in order to avoid further aliasing in the Fourier transform operations required in Step (2). This extrapolation has a scale length of twice the single-dish beam, in order to avoid spurious Fourier components.

In detail, UV\_SHORT (or XY\_SHORT) performs the following operations:

- Resampling (in space) of the original spectra on a regular grid by convolution with a small (typically 1/4 of the single-dish beam) gaussian convolving kernel. In this process, the weights of individual spectra is carried on a weight map.
- Extrapolation by zero outside the convex hull of the mapped region.
- Convolution of the result by a gaussian twice as wide as the single-dish beam. Within the convex hull of the mapped region, the smoothed map is replaced by the original map.

### 20.21.6 UV\_SHORT Step\_2

Step (2) Extraction of UV visibilities from this map.

From the given input data cube, or the "well behaved" data cube created by Step (1), UV\_SHORT computes the visibilities in the following way:

- Fourier transform of the single dish map;
- Division by the Fourier transform of the single dish beam, up to a maximum spacing (SHORT\_SD\_DIAM, in meters);
- Inverse Fourier transform to the image plane and then for each pointing center;
- Multiplication of the image by the primary beam of the interferometer elements;

- Fourier transform back to the UV plane;
- Creation of the visibilities, with a given weight `SHORT_SD_WEIGHT` and an appropriate calibration factor to Janskys `SHORT_SD_FACTOR`.

Both the single-dish and the interferometer antennas are assumed to have gaussian beams (`SHORT_SD_BEAM` and `SHORT_IP_BEAM`, in radians).

#### 20.21.7 UV\_SHORT Variables:

Control variables for `UV_SHORT` are not predefined, except for the 3 main ones: `SHORT_SD_FACTOR`, `SHORT_SD_WEIGHT` and `SHORT_UV_TRUNC`.

All others should be defined by the user in case the default value is not appropriate, with their appropriate (Real, Char or Logical) types.

#### 20.21.8 SHORT\_DO\_SINGLE

Logical value, should be YES except for test purposes.

#### 20.21.9 SHORT\_DO\_PRIMARY

Logical value, should be YES except for test purposes.

#### 20.21.10 SHORT\_FTOLE

The tolerance in frequency / velocity alignment. The default is 0.1 channel at edges.

#### 20.21.11 SHORT\_IP\_BEAM

Half-power beam width of the interferometer antennas, in radians. The beam is assumed to be gaussian.

Default value is 0, meaning that the beam is taken from the Telescope section if present.

### 20.21.12 SHORT\_IP\_DIAM

Interferometer diameter for which UV\_SHORT will compute short spacing visibilities.

Default value is 0, meaning that the diameter is taken from the Telescope section if present.

### 20.21.13 SHORT\_MCOL

\*\*\* Obsolescent \*\*\*

See READ SINGLE ClassTable.tab /RANGE command for an equivalent method of selecting the appropriate channel range.

The first and last column to be mapped. For tables produced by GRID command of CLASS, SHORT\_MCOL[1] should be 4 and SHORT\_MCOL[2] can be set to 0 to process all channels.

Default value: 4 0, appropriate for tables coming from CLASS\GRID command.

### 20.21.14 SHORT\_MIN\_WEIGHT

The minimum weights under which a given point in the map should be filled by the smooth map rather than by the gridded (original) map.

Default value: 0.01

### 20.21.15 SHORT\_MODE

This is an integer code used for backward compatibility with an older version of the UV\_SHORT task, and also for test purpose.

Allowed values are :

- 1 indicates to create a single UV table with columns for the Phase center offsets only
- 2 indicates to create a UV table with columns for the Pointing center offsets
- 3 indicates to create a UV table with the additional columns



- type being Pointing or Phase, as in the original UV\_TABLE\$
- 4 Allow to override the antenna diameter in the Telescope section
  - +1 indicates to append to the initial UV table the short spacings with Phase center offsets (which must thus match the initial UV table shape)
  - +2 indicates to append to the initial UV table the short spacings with Pointing center offsets (which must thus match the initial UV table shape)
  - +3 indicates to append to the initial UV table the short spacings (The extra column type being determined automatically).
  - +4 Allow to override the antenna diameter in the Telescope section

The default value is 3, i.e. automatic merging with the current UV table.

#### 20.21.16 SHORT\_SD\_BEAM

Half-power beam width of the single dish antenna, in arcseconds. The beam is assumed to be gaussian.

Default value is 0, meaning that the beam is taken from the Telescope section if present.

#### 20.21.17 SHORT\_SD\_DIAM

Single dish diameter used to produce the input spectra, in meters.

Default value is 0, meaning that the diameter is taken from the Telescope section if present.

#### 20.21.18 SHORT\_SD\_FACTOR

Multiplicative calibration factor; it is used to convert from the single dish map units (e.g., main-beam brightness temperature) to janskys.

A default value of 0 can be used if the original data file is in unit of Tmb, the main beam brightness temperature, because in this case the conversion factor can be derived from the beam size. UV\_SHORT will complain if it cannot derive the appropriate value.

### 20.21.19 SHORT\_SD\_WEIGHT

Weight scaling factor for the generated visibilities.

It is a relative scaling factor in the weights compared to a supposedly optimal weighting to give the best combined synthesized beam. That optimal weighting essentially gives the same weight density per unit area in the UV plane than the shortest baselines measured with the interferometer only. However, if the single-dish data has not been observed long enough, or has baseline problems for example, this weight may add noise to the overall data set, so could be down-weighted.

Default: 1.0

### 20.21.20 SHORT\_TOLE

The tolerance in position (in radians). The behaviour differs for Short and Zero spacings and Table or 3-D cubes as Single-Dish data.

If the Single-Dish data is a table of spectra, Spectra differing by less than this amount will be added together prior to gridding. A recommended value is below 1/10th of the Single Dish primary beam. This is valid for Short Spacings and Zero Spacing cases.

If the Single-Dish data is 3-D data cube, SHORT\_PTOLE is used only for Zero Spacings. If no pixel is within SHORT\_PTOLE of an Interferometer pointing center, no short spacing is added for this field and an error occurs.

Default value is 0, meaning using 1/16th of the Single Dish primary beam.

### 20.21.21 SHORT\_UV\_MAX

No visibility at spacings higher than SHORT\_UV\_MAX is generated. Theoretical consideration on the method used in this task implies that SHORT\_UV\_MAX should be at most (SHORT\_SD\_DIAM-SHORT\_IP\_DIAM). Smaller values may need to be applied if, for example, the pointing accuracy of the Single Dish is insufficient.

Default value is 0, meaning to use SHORT\_SD\_DIAM-SHORT\_IP\_DIAM

### 20.21.22 `SHORT_UV_MIN`

No visibility at spacings shorter than `SHORT_UV_MIN` is generated. If the "short spacing" data comes from a single-dish, this value could be set to Zero.

However, if, for example, one uses an ACA image as short spacings for an ALMA data set, the shortest baseline is the ACA antenna diameter, 7 m. `SHORT_UV_MIN` should then be set to 7 in this case (unless the ACA image includes the total power data in it already).

Default value is 0.

### 20.21.23 `SHORT_WCOL`

For tests only: The column of the spectra table containing the weights.

Default value: 0=3, appropriate for tables coming from `CLASS\GRID` command.

### 20.21.24 `SHORT_WEIGHT_MODE`

The weighting mode (`NATURAL`, `UNIFORM` or `GRIDDED`). It is advised to use 'NA' for Natural weighting. Other values are reserved for tests.

### 20.21.25 `SHORT_XCOL`

For tests only: The column of the spectra table containing X offsets.

Default value: 0=1, appropriate for tables coming from `CLASS\GRID` command.

### 20.21.26 `SHORT_YCOL`

For tests only: The column of the spectra table containing Y offsets.

Default value: 0=2, appropriate for tables coming from CLASS\GRID command.

## 21 BUNDLES Language Internal Help

### 21.1 Language

```

COMBINE      : Combine Images with automatic resampling
EXPLORE      : Make a plot of spectra around a 2-D map
KEPLER       : Optimal line detection for Keplerian disk
SELF CAL     : Perform a self calibration
SPECTRAL_CLEAN : Multi-Spectral Spatial Deconvolution
UV_DETECT    : UV plane matched filter detection tool

```

### 21.2 COMBINE

```

[BUNDLES\]COMBINE OutCube CODE In1 In2 [Off] [/FACTOR A1 A2]
[/THRESHOLD T1 T2] [/BLANKING Bval]

```

or

```

[BUNDLES\]COMBINE OutCube = [A1*]In1 Oper [A2*]In2 [Off]
[/THRESHOLD T1 T2] [/BLANKING Bval]

```

This is a superset of the MAP\_COMBINE command, that automatically resamples and reproject the In1 and/or In2 data sets so that they match spatially (according to In1) and spectrally (when both are data cubes).

See HELP MAP\_COMBINE for details on the combination codes, factors, thresholds and blanking.

#### 21.2.1 COMBINE CODE

```

[BUNDLES\]COMBINE OutCube CODE In1 In2 [Off] [/FACTOR A1 A2]
[/THRESHOLD T1 T2] [/BLANKING Bval]

```

CODE is the operation code. Allowed values are

```

ADD      or PLUS      OutCube = A1*In1 + A2*In2 + Off
SUBTRACT or MINUS     OutCube = A1*In1 - A2*In2 + Off
DIVIDE   or OVER      OutCube = A1*In1 / A2*In2 + Off
MULTIPLY or TIMES     OutCube = A1*In1 * A2*In2 + Off
OPACITY              OutCube = -Log( A1*In1 / A2*In2 + Off)
INDEX                OutCube = Log( A1*In1 / A2*In2) / Log(Nu1/Nu2)

```

where Nu1 is the Frequency of In1, and Nu2 that of In2. Off is 0 if not specified.

Cube, In1 and In2 are names of files or SIC Image variables, depending on whether a dot (.) is present in them or not.

### 21.2.2 COMBINE /BLANKING

```
[BUNDLES\]COMBINE OutCube CODE In1 In2 [/FACTOR A1 A2]
[/THRESHOLD T1 T2] /BLANKING Bval
```

Specify the Blanking value to be used in the OutCube. If not specified, the Blanking from In1 is used instead, and that of In2 if In1 has no Blanking.

### 21.2.3 COMBINE /FACTOR

```
[BUNDLES\]COMBINE OutCube CODE In1 In2 /FACTOR A1 A2
[/THRESHOLD T1 T2] [/BLANKING Bval]
```

Specify the factors to apply to In1 and In2. Default is 1.0

### 21.2.4 COMBINE /THRESHOLD

```
[BUNDLES\]COMBINE OutCube CODE In1 In2 [/FACTOR A1 A2]
/THRESHOLD T1 T2 [/BLANKING Bval]
```

Specify the thresholds above which the computation is valid for In1 and In2. For pixels below this threshold, the OutCube is blanked.

Default is no threshold (-huge(0)).

## 21.3 KEPLER

```
[BUNDLES\]KEPLER [?|DataCube|INIT|SHOW [Arg]] [/MASK File Threshold]
[/RESET [Script] [/VSYSTEM Value] [/VELOCITY R function(R)]
[/HFS File [Opacity]]
```

Re-align spectra from a rotating thin disk according to the projected rotation velocity at any point in the disk, and computes the combined integrated spectrum and brightness radial distribution. The projection assumes a thin disk (no flaring). By default, the disk is assumed to be in Keplerian rotation.

The command is controlled by a set of KEPLER\_\* variables, whose values can be verified by KEPLER ? and modified by the user. In addition to the built-in KEPLER\_\* variables, KEPLER\_RMAX indicates the radius

DataCube is the name of the data cube to be used. It can be a SIC 3-D variable or the name of a GILDAS (or FITS) data file. The default is CLEAN.

### 21.3.1 KEPLER INIT

KEPLER INIT

Declare and Initialize all KEPLER related variables. This may be needed to specify some of them before further use of the KEPLER command.

### 21.3.2 KEPLER SHOW

KEPLER SHOW Name|? [/HFS File.hfs [Opacity]]

or

SHOW KEPLER Name|?

KEPLER SHOW ? will list the control parameters of command KEPLER SHOW.

Command KEPLER SHOW Name (where KEPLER\_Name is any of the result variable names, i.e. Name can be PV, PROFILE, SPECTRUM, or VELO) can be used to graphically display the results. KEPLER SHOW ALL will display a combined plot.

KEPLER SHOW SPECTRUM and KEPLER SHOW ALL also perform a Gaussian fit into the integrated line profile to derive the integrated flux, the disk systemic velocity (if the option /VDISK was not present) and the line width.

### 21.3.3 KEPLER /HFS

KEPLER SHOW Name /HFS File.hfs [Opacity]

Use an Hyperfine structure file, described in File.hfs to fit the velocity re-aligned, integrated spectrum. The corresponding hyperfine structure is stored in SIC structure HFS%. The optional argument Opacity can be used to specify the total opacity (sum over the hyperfine components), the default being 0.1. If Opacity is negative, the opacity is then adjusted by the profile fitting procedure, using -Opacity as starting value.

Fit results are available in SIC structure G\_%...

### 21.3.4 KEPLER /MASK

[BUNDLES\]KEPLER /MASK [File [Threshold]] [/VSYSTEM Value] [/VELOCITY R function(R)]

(Experimental)

Generate an approximate spatial mask for further use, e.g. in CLEAN or other masking operations. The brightness is assumed to decrease with radius, and a local line width of 0.3 km/s is assumed to derive the channel-dependent mask. Convolution by the current Clean beam is performed.

If a File argument is present, the resulting mask data cube is stored in File (with default extension

If present, Threshold (in range [0,1]) indicates that pixels below the apparent peak brightness times the Threshold should be out of the mask (i.e. have a value 0), the others in the mask (a value 1).

If Threshold is not present, the mask values are just taken "as is", without being re-mapped to a 0,1 mask. A simple SIC formula can be used to convert them to a 0,1 mask later.

### 21.3.5 KEPLER /RESET

KEPLER /RESET [Script]

Deletes the result variables (see HELP KEPLER Results) and, if present, executes the specified Script file that can contain any command to reset the KEPLER\_... input variables.

### 21.3.6 KEPLER /VELOCITY

[BUNDLES\]KEPLER [/VSYSTEM Value] /VELOCITY R Function(R)

Use the functional form specified by Function(R) for the rotation velocity as a function of Radius. The default is the Keplerian law  $KEPLER\_VMASS \cdot \sqrt{R/100}$ .

Note: This can allow to use the KEPLER command to handle rotation curves for galaxies, for example. However, the choice of radial units is not obvious in this case. It can be made simple by setting the "distance" KEPLER\_DIST to 1 pc, so that the radii R are then just in arcsecond.

### 21.3.7 KEPLER /VSYSTEM

KEPLER [DataCube] /VSYSTEM [Value] [/VELOCITY R Function(R)]

Specify that radial profile should be computed at velocity KEPLER\_VDISK (and optionally reset KEPLER\_VDISK = Value]. No fit for the disk velocity is performed by KEPLER SHOW PROFILE after that.



### 21.3.8 KEPLER /WIDGET

#### KEPLER /WIDGET

Activate the Widget to control KEPLER command variables and actions. Still under development, so all functions may not be controlled in this way. , e.g. no HFS mode, no velocity function control yet.

### 21.3.9 KEPLER Variables:

Most input variables are pre-defined by the code. The exception is KEPLER\_RMAX, which can be defined by the user but has a default value derived from KEPLER\_ROUT otherwise.

#### 21.3.10 KEPLER\_X0

X offset of disk center (in arcsec)

#### 21.3.11 KEPLER\_Y0

Y offset of disk center (in arcsec)

#### 21.3.12 KEPLER\_ROTA

Position angle of the projection of the disk rotation axis (in degree, East from North)

#### 21.3.13 KEPLER\_INCLI

Disk inclination (in degree)

#### 21.3.14 KEPLER\_DIST

Disk distance (in pc).

#### 21.3.15 KEPLER\_VMASS

Disk rotation velocity at 100 au in km/s. Should be equal to  $2.98 * \sqrt{M/M_{\text{sun}}}$  from Kepler laws.

#### 21.3.16 KEPLER\_RMIN

Inner radius for the Radius-Velocity diagram (in au).

### 21.3.17 KEPLER\_RMAX

Outer radius for the Radius-Velocity diagram (in au).  
KEPLER\_RMAX must be greater than KEPLER\_ROUT.

KEPLER\_RMAX is an optional variable. By default (i.e. if the variable has not been created by the user), the maximum radius is taken as  $\text{KEPLER\_ROUT} + 5 \times \text{KEPLER\_STEP}$ .

### 21.3.18 KEPLER\_RINT

Inner radius (in au) for the integrated spectrum, computed by summing up spectra from KEPLER\_RINT to KEPLER\_ROUT.

### 21.3.19 KEPLER\_ROUT

Outer radius (in au) for the integrated , computed by summing up spectra from KEPLER\_RINT to KEPLER\_ROUT.

### 21.3.20 KEPLER\_STEP

Sampling step in au. Must be compatible with the angular resolution.

Note that the spectral resolution allows some gain in spatial resolution compared to the beam size.

### 21.3.21 KEPLER\_THETA

Maximum angle (in degree) from the disk projected major axis beyond which the spectra are not considered in the averaging process.

This angle is needed because the projected rotation velocity is degenerate to zero along the minor axis, which results in a lower effective angular resolution in this direction. This effect depends on the disk inclination: a larger angle can be used for less inclined disks.

The default is 60 degree. The Azimut coverage can be visualized using command `SHOW KEPLER_VELO`.

### 21.3.22 KEPLER\_AZIMUT

KEPLER\_0 in the computation (Azimut Zero corresponds to the oriented minor axis, i.e. is at KEPLER\_ROT in the sky plane).

For example 90 270 indicates Az between 90 and 270 degrees, while 270 90 indicates As from 0 to 90 and 270 to 360.

The Azimut coverage can be visualized using command `SHOW KEPLER_VELO`.

### 21.3.23 KEPLER\_VDISK

KEPLER\_VDISK is a variable that indicates the disk systemic velocity (in km/s). The value is always used to define the velocity field (see KEPLER\_VELO result variable).

However, for the radial profile, the usage depends on the /VSYSTEM option. When /VSYSTEM is not present, the radial profile is taken as the maximum brightness of the integrated, velocity aligned, spectrum for at each radius. When /VSYSTEM option is present, the radial profile is taken at the velocity KEPLER\_VDISK.

### 21.3.24 KEPLER\_STRICT

KEPLER\_STRICT is an optional (user-created) logical variable that specifies whether a spectrum is computed or not when the full velocity range is not covered. Default is NO, i.e. spectra not covering the full range are not flagged.

### 21.3.25 Results:

The KEPLER command produces 2 SIC Tables, KEPLER\_SPECTRUM, and KEPLER\_PROFILE, and two SIC 2-D Images, KEPLER\_PV and KEPLER\_VELO that are available as SIC variables for further writing or plotting.

Command SHOW KEPLER Name (where KEPLER\_Name is any of the above variable names) can be used to graphically display these variables. SHOW KEPLER ALL will display a combined plot. The SHOW KEPLER command behaviour is controlled by the variables in structure KEPLER\_SHOW%.

SHOW KEPLER SPECTRUM and SHOW KEPLER ALL also perform a Gaussian fit into the integrated line profile to derive the integrated flux, the disk systemic velocity (if the option /VSYSTEM was not present in the KEPLER command) and the line width.

### 21.3.26 KEPLER\_PROFILE

Radial profile of the peak brightness temperature. The peak brightness temperature is that appearing at KEPLER\_VDISK if /VDISK option was present, or at the velocity defined by the maximum of the integrated spectrum. This is a 3 column table containing the radii (in au), the brightness (in K) and an estimate of its error.

**21.3.27 KEPLER\_PV**

Velocity-aligned spectra as a function of radius. This is a 2-D image (equivalent to a Nrad column table) containing the spectra (averaged brightness temperature) for each of the Nrad radii defined by the sampling KEPLER\_RINT, KEPLER\_RMAX and KEPLER\_STEP.

The velocities are defined in KEPLER\_SPECTRUM[1], but also derived from the axis description of this 2-D image.

**21.3.28 KEPLER\_SPECTRUM**

Velocity-aligned, disk-integrated spectrum, over the region defined by KEPLER\_RINT, KEPLER\_ROUT and KEPLER\_THETA. This is a 3 column table containing the velocities (km/s) in column 1, the flux in column 2, and an estimate of the flux error in column 3.

**21.3.29 KEPLER\_VELO**

Velocity field in the region retained by the KEPLER command. This contains the line-of-sight projected velocity offset from the (assumed) disk systemic velocity KEPLER\_VDISK.

**21.3.30 Display:**

The results of the KEPLER command can be displayed in several ways by command KEPLER SHOW. The command behaviour is controlled by variables in the structure KEPLER\_SHOW%.

**21.3.31 KEPLER\_SHOW**

KEPLER\_SHOW% is a Structure variable controlling how the display of the KEPLER SHOW (or SHOW KEPLER) command is handled. It contains the following variables, that can be listed by KEPLER SHOW ?

Show Mean Spectrum	KEPLER_SHOW%SPEC	[ NO ]
Show Radial Profile	KEPLER_SHOW%PROF	[ NO ]
Show PV diagram	KEPLER_SHOW%PV	[ NO ]
Select compact layout	KEPLER_SHOW%LAYOUT	[ NO ]
Velocity Range	KEPLER_SHOW%V	[ 0 0 ]
Radius Range	KEPLER_SHOW%R	[ 0 0 ]
Temperature Range	KEPLER_SHOW%T	[ 0 0 ]
Flux Range	KEPLER_SHOW%F	[ 0 0 ]

**21.3.32 KEPLER\_SHOW%V**

Velocity range for the displays (R-V diagram and Spectrum),  
in km/s.

**21.3.33 KEPLER\_SHOW%R**

Radius range for the displays (R-V diagram and Radial Pro-  
file), in au.

**21.3.34 KEPLER\_SHOW%T**

Temperature range for the display (R-V diagram), in K

**21.3.35 KEPLER\_SHOW%F**

Flux range for the displays (Spectrum), in Jy.

**21.3.36 KEPLER\_SHOW%LAYOUT**

If YES, use a compact layout. If NO use layout with equal  
panel sizes. This only applies to KEPLER SHOW ALL.

**21.4 SELF CAL**

SELF CAL [ ? | AMPLI | APPLY | PHASE | SUMMARY | SHOW [Last [First]] ] [ /WID-  
GET ]

Command to perform Self Calibration (even on spectral line data). The  
solution is computed, saved and/or applied.

The arguments control the action.

SELF CAL ?	Lists the self calibration parameters
SELF CAL AMPLI	Compute an Amplitude only self calibration
SELF CAL APPLY	Apply the computed solution
SELF CAL FLAG []	Flag data according to self calibration correction
SELF CAL PHASE	Compute a Phase only self calibration
SELF CAL SHOW []	Show the computed corrections
SELF CAL SAVE	Save self calibration parameters in selfcal.last
SELF CAL SUMMARY	Display the improvements in Noise & Dynamic range and calibration status

**21.4.1 SELF CAL /WIDGET**

SELF CAL /WIDGET

Activates the widget interface to perform self calibration (even on spectral line data set). A continuum data set is extracted from the specified channel range, with all selected channels averaged to provide improved sensitivity to find a solution.

The buttons control the action.

AMPLI	Perform an Amplitude only self calibration
PHASE	Perform a Phase only self calibration
Continue	Continue execution when the script is in Pause
APPLY	Apply the solution
FLAG	Flag data according to self calibration correction
INPUT	List parameters (as in SELFCAL ?)
SAVE	Save the parameters in selfcal.last
SHOW	Show the computed corrections
SUMMARY	Display the improvements in Noise & Dynamic range

#### 21.4.2 SELFCAL Arguments:

The arguments control the action.

SELFCAL ?	Lists the self calibration parameters
SELFCAL AMPLI	Perform an Amplitude only self calibration
SELFCAL APPLY	Apply the solution
SELFCAL FLAG []	Flag data according to self calibration correction
SELFCAL PHASE	Perform a Phase only self calibration
SELFCAL SAVE	Save the parameters in selfcal.last
SELFCAL SHOW []	Show the computed corrections
SELFCAL SUMMARY	Display the improvements in Noise & Dynamic range

#### 21.4.3 AMPLITUDE

SELFCAL AMPLI

Compute an Amplitude only self-calibration. The integration times, SELF\_TIME, should in general be significantly larger than for a Phase only self-calibration.

SELFCAL automatically adjusts the gains so that their mean is 1.0, to avoid changing the flux scale.

#### 21.4.4 APPLY

SELFCAL APPLY [Type [Gain]]

Apply the self calibration solution. This is done only if the return status from the previous computation, SELF\_STATUS, is greater than 0. SELFCAL APPLY automatically saves the parameters and results in the "selfcal-AMPLI.last" or "selfcal-PHASE.last" file, depending on the Type of solution applied.

Type is the type of solution to apply. The default is 'SELF\_MODE', i.e. PHASE or AMPLI depending on the last type of self-calibration computed. Type can also take the DELAY value, where the "phase" corrections are interpreted as atmospheric path changes and scale as Frequency.

Gain is an optional gain factor (default is 1.) on the correction.

#### 21.4.5 FLAG

SELF CAL FLAG [Threshold]

Flag data which have no valid correction, or a correction above the specified Threshold (in degrees, > 0 for PHASE, no units, > 1 for AMPLI). The mode (AMPLI, PHASE or DELAY) is taken from the default mode 'SELF\_MODE'. No correction is applied however.

With the Widget interface, no Threshold can be specified.

#### 21.4.6 INPUT

SELF CAL INPUT or SELF CAL ?

Display SELF CAL control variables

#### 21.4.7 PHASE

SELF CAL PHASE

Compute a Phase-only self calibration. The integration time should be short enough to correct for atmospheric errors, but large enough to obtain significant signal to noise for most antennas.

#### 21.4.8 SAVE

SELF CAL SAVE

Save the parameters and results in the "selfcal.last" file.

#### 21.4.9 SHOW

SELF CAL SHOW [Last [First]]

Shows the correction computed by self calibration. By default, the difference between the last two iterations is displayed: phase should be around 0, and amplitude around 1 if the solution is converged.

If Last and First are present, it shows the difference between these two specified iteration. If Last only is present, it shows the total correction between the original data and that iteration.

The displayed ranges are controlled by SELF\_ARANGE[2] (limits of Amplitude gain), SELF\_PRANGE[2] (limits of Phase correction) and SELF\_TRANGE[2] (limits for time axis).

#### 21.4.10 SUMMARY

##### SELFAL SUMMARY

Display a summary of the Self-calibration process: type of calibration, rms and dynamic range at each iteration, as well as the number of flagged or uncalibrated visibilities.

#### 21.4.11 Results:

SELFAL returns results in several variables, creates a CGAINS array containing the Gain values, and one file to display the computed correction. The file name is specified by SELF\_SNAME.

The result variables are:

SELF\_APPLIED

Indicates whether the solution has been applied

SELF\_STATUS

Indicates if a solution has been computed

SELF\_DYNAMIC[Self\_Loop+1]

The dynamic range at each iteration

SELF\_RMSCLEAN[Self\_Loop+1]

The rms noise at each iteration

#### 21.4.12 SELF\_APPLIED

Variable SELF\_APLPLIED indicates whether a solution has been applied (#0) or not (0). The value indicates the type and quality of solution, as for SELF\_STATUS



### 21.4.13 SELF\_STATUS

Variable SELF\_STATUS indicates if a solution has been computed

0 no solution  
+/- 1 Phase solution  
+/- 2 Gain solution  
>0 means a good solution, <0 a poor one.

### 21.4.14 SELF\_DYNAMIC

SELF\_DYNAMIC is a variable length array of size Self\_Loop+1, containing the dynamic range at each iteration.

### 21.4.15 SELF\_RMSCLEAN

SELF\_RMSCLEAN is a variable length array of size Self\_Loop+1, containing the Clean map rms noise at each iteration.

### 21.4.16 Variables:

The SELFICAL behaviour can be adjusted through control variables named SELF\_... (see EXA SELF\_ for a list), in addition to the control variables of UV\_MAP (MAP\_...) and CLEAN (CLEAN\_...)

The most important variable is SELF\_TIMES, a variable length array which controls the integration time at each loop. SELF\_NITER and SELF\_MINFLUX also control the number of Clean components and minimum flux retained in each loop. The size of these arrays define the number of loops.

See HELP SELFICAL SELF\_LOOP to find out how to control the number of loops.

### 21.4.17 SELF\_CHANNEL

SELF\_CHANNEL[2]

First and last channel to define the range to compute the UV table for the self-calibration solution. For example, if you have used UV\PLUGC to plug a continuum data into the last channel, this could be set to the number of channels. 0 0 means all channels are averaged to compute the "continuum" image.

### 21.4.18 SELF\_COLOR

#### SELF\_COLOR

Controls the LUT color range at each self-calibration cycle if non Zero. Since the dynamic range evolves, this can be a useful way to highlight the gain. If non Zero, SELF\_COLOR is passed as argument to a COLOR command executed at each cycle after display.

Practical values for SELF\_COLOR are -8 ("bright" version, highlights the noise level) or +8 ("dark" version, hides the noise), but lower absolute values may be needed for higher dynamic ranges.

See HELP COLOR for details.

### 21.4.19 SELF\_LOOP

Number of self-iteration loops. It is a ReadOnly variable that is automatically computed from the size of the SELF\_TIMES, SELF\_NITER and SELF\_MINFLUX arrays.

These variable length arrays can be resized using the LET /RESIZE command. For example

```
LET SELF_TIMES 40 20 10 /RESIZE
will lead to an array of 3 elements, SELF_TIMES[3].
```

SELF\_TIMES, SELF\_NITER and SELF\_MINFLUX must be of equal size. To simplify the process, constant arrays are assumed of arbitrary length in this determination. If all 3 arrays have constant values, SELF\_TIMES determines the number of loops.

Constant arrays are assumed of arbitrary length in this determination. If all 3 arrays have constant values, SELF\_TIMES determines the number of loops.

### 21.4.20 SELF\_NITER

Variable length array specifying the number of Clean components retained for each loop of the self-calibration process. Default is 0, meaning all Clean components found by CLEAN.

For simple structures and Phase calibration, 10 may be enough. For more complex ones, be sure to include enough Clean components in the model. More components can be taken at each step, although the better knowledge of phase errors often allows the source to be represented with a smaller

number of components after self-calibration than before. The default is a reasonably good compromise, although faster convergence may be obtained with smaller number of components.

This variable length array can be resized using the LET /RESIZE command. For example

```
LET SELF_NITER 10 0 0 /RESIZE
```

will lead to 3 self-calibration loops (if SELF\_TIMES and SELF\_MINFLUX are also of size 3), the first one selecting only 10 components, the two others all components.

#### 21.4.21 SELF\_TIMES

Variable length array specifying the integration time (in seconds) for each loop of the self-calibration process.

At NOEMA, 45 sec is the normal minimum integration time. Depending on Signal to Noise, you may need to have this longer, e.g. 120 sec. For several loops, start with a longer value, and decrease only at the end.

At ALMA, the minimum integration time is 6 sec. At VLA, this may be as small as 1 sec.

It is recommended to use the same integration time for the last two iterations, to simplify the interpretation of the results and of the SELF-CAL SHOW display.

This variable length array can be resized using the LET /RESIZE command. For example

```
LET SELF_TIMES 180 90 45 /RESIZE
```

will lead 3 self-calibration loops (if SELF\_TIMES and SELF\_MINFLUX are also of size 3) with decreasing integration times.

#### 21.4.22 SELF\_MINFLUX

Variable length array specifying the minimum flux density (in Jy/beam) to be considered in the Clean image for each loop of the self-calibration process. Note that this is the brightness of a pixel, not the flux of a Clean component.

This variable length array can be resized using the LET /RESIZE command. For example

```
LET SELF_MINFLUX 0.001 0 0 /RESIZE
```

will lead 3 self-calibration loops (if SELF\_TIMES and SELF\_NITER are al-

so of size 3) selecting on regions brighter than 1mJy/beam in the first one, and all regions in the last 2 ones.

#### 21.4.23 SELF\_REFANT

The reference antenna number. If 0, the program will peak the one with the shortest average baselines.

#### 21.4.24 SELF\_FLUX

Maximum value in the FLUX window. If 0, the FLUX window of Clean is not displayed

#### 21.4.25 SELF\_PRECISION

Tolerance to test for self-calibration convergence. The default is 0.01. SELFCAL SUMMARY will write a message when no more selfcal iteration improves the solution (noise and dynamic range) at this precision level.

#### 21.4.26 SELF\_RESTORE

Use UV\_SELF /RESTORE after Cleaning. This avoids signal aliasing at image edges, and leads to a better estimate of the noise level.

It also allows to use smaller images, in practice,

#### 21.4.27 SELF\_DISPLAY

If YES, display Clean image before each calibration loop, and prompt for user input. If YES, Cleaning at each step will use the number of iterations specified by NITER, while if set to NO, Cleaning will stop at SELF\_NITER, saving time.

The dynamic range progress report is accurate only if SELF\_DISPLAY is set.

#### 21.4.28 SELF\_FLAG

If SELF\_FLAG is YES, SELFCAL will flag data with no solution. If NO, it will keep the data as it was before.

#### 21.4.29 SELF\_SNR

Minimum Signal to Noise ratio on the antenna gain to consider a solution to be valid for an antenna. 6 is a good value, 3 a lower limit. Beware that this SNR makes sense only if the a priori estimate of the noise from the UV weights is correct: see SELF\_SNOISE.

#### 21.4.30 SELF\_SNOISE

Noise scaling factor. This should be 1, but some noise estimates need corrections. Continuum data from ALMA often requires  $\sqrt{2}$  instead, for example. Command UV\_PREVIEW may help you checking the noise scale.

#### 21.4.31 CLEAN\_ARES

Maximum absolute residual to stop Cleaning

#### 21.4.32 CLEAN\_FRES

Maximum fractional residual to stop Cleaning

#### 21.4.33 CLEAN\_NITER

Maximum number of Clean components. If all of CLEAN\_ARES, CLEAN\_FRES and CLEAN\_NITER are 0, Clean stops by checking the stability of the cleaned flux over CLEAN\_NKEEP iterations. See HELP CLEAN for details.

### 21.5 SPECTRAL\_CLEAN

[BUNDLES\]SPECTRAL\_CLEAN MODE [Control ]

Perform a Clean with different spectral scales.

MODE can be

FFT	Clean the Fourier Transform of the spectra
WAVE	Clean a Wavelet Transform of the spectra
DUAL Ns	Clean at two different spectral resolutions
MULTI Ns	Clean at two (or more) spectral resolutions.

Instead of Cleaning separately individual channels, SPECTRAL\_CLEAN cleans either Spectral Transform of the data cube (along the velocity axis), and performs the inverse transformation to restore the channel-based Clean components.

The SPECTRAL\_CLEAN method can improve deconvolution of spectrally well resolved faint line wings, yielding more accurate integrated line fluxes, at the cost of some extra computations. However, SPECTRAL\_CLEAN can be hampered by strong velocity gradient, that require supports that differ widely among channels.

Standard CLEAN control parameters apply. However the METHOD must allow retrieving Clean Componentes: MRC is thus excluded. SPECTRAL\_CLEAN can also work on Mosaics.

### 21.5.1 SPECTRAL\_CLEAN DUAL

[BUNDLES\]SPECTRAL\_CLEAN DUAL NSmooth

In DUAL mode, SPECTRAL\_CLEAN cleans a (spectrally) smoothed version of the data cube, and the difference between this smooth version and the original ones. The two Clean component tables are then merged to restore the final image using UV\_RESTORE.

NSmooth is the number of channels being smoothed together.

The DUAL methods involves Cleaning two data cubes, so is a somewhat slower than a simple CLEAN. SPCLEAN%MEMORY indicates whether intermediate results are kept in memory (faster) or on temporary files (slower, but allowing to work on larger files).

Mode MULTI should in general be preferred, but does not include the final UV\_RESTORE.

### 21.5.2 SPECTRAL\_CLEAN FFT

[BUNDLES\]SPECTRAL\_CLEAN FFT

Clean the Fourier Transform along the spectral axis of the DIRTY cube, and transform back the Clean components to retrieve the per-channel Clean components. The final Clean image is produced using UV\_RESTORE.

The usual Clean convergence parameters apply, although CLEAN\_NKEEP may need small adjustment because of the non-positive nature of the signal.

The Fourier Transform leads to a Complex valued data set, whose Hermiticity is not considered. Real and Imaginary parts are cleaned separately, so the method is about twice slower than a standard Clean.

### 21.5.3 SPECTRAL\_CLEAN MULTI

```
[BUNDLES\]SPECTRAL_CLEAN MULTI Ns1 [Ns2 ...]
```

Clean a (spectrally) smoothed version of the data cube, then start from this result to continue Cleaning with the original spectral resolution.

To be implemented: the method can be generalized to more than 1 smoothing scale, by performing the smoothing in descending order ( $Ns1 > Ns2 > \dots > 1$ ). This may allow to catch signals that have widely different widths.

### 21.5.4 SPECTRAL\_CLEAN WAVE

```
[BUNDLES\]SPECTRAL_CLEAN WAVE
```

Clean a Wavelet Transform along the spectral axis of the DIRTY cube, and transform back the Clean components to retrieve the per-channel Clean components. The final Clean image is produced using UV\_RESTORE.

The noise level is not the same for the wavelet components of the data cube: this is taken into account by the method to Clean each wavelet image plane to its proper noise level.

Apart for the time required by the Wavelet transform, the method has a comparable speed to a standard Clean.

## 21.6 UV\_DETECT

```
[BUNDLES\]UV_DETECT [Result] [/FILE UVData ImageData]
```

```
[BUNDLES\]UV_DETECT [Result]
```

Apply a matched filter defined by the CLEAN image to the current UV

data and save results as above. It is recommended that the continuum emission has been removed before, e.g. using UV\_BASELINE.

Result.uvt will be a pseudo UV table with only the (0,0) visibility, which can be viewed by UV\_PREVIEW.

Result.dat is a column data file, useable in GreG by command COLUMN. Column 1 is the velocity, 2 the frequency, 3 the filter intensity.

The default for argument Result is gag\_scratch:detect.

### 21.6.1 UV\_DETECT /FILE

```
[BUNDLES\]UV_DETECT [Result] /FILE UVData[.uvt] ImageData[.lmv-clean]
```

Apply a matched filter defined by the image model available in file ImageData (default extension .lmv-clean) to the UV data set available in file UVData (default extension .uvt), and save the filtered result into files Result.uvt and Result.dat. Continuum emission is automatically removed using UV\_BASELINE, with line windows defined by UV\_PREVIEW.

If argument Result is not present, the intermediate files are stored in  
gag\_scratch::detect.uvt and gag\_scratch:detect.dat

### 21.6.2 UV\_DETECT Algorithm

The UV\_DETECT algorithm is basically that described by Loomis et al 2018 (2018AJ....155..182L, see <https://arxiv.org/pdf/1803.04987.pdf>). Here, instead of being implemented as a Python / CASA script, it is coded in Fortran and embedded into IMAGER. UV\_DETECT calls an imager script that reads the data set, computes a UV\_MODEL from the ImageData using the UV coverage found in the UV data set, resamples this UV\_MODEL at the same velocity resolution than the UV data, and ultimately calls command UV\_CORRELATE to apply the UV plane filter.

As described in the original paper, the UV data set and source model available in ImageModel must have the same centering. The ImageModel must also cover a sufficient width around its specified source velocity.

The command will complain if the smoothing kernel described by the ImageModel is insufficient.



## 22 IMAGER Language Internal Help

### 22.1 Language

CLARK	Shortcut to CLEAN with CLARK Method
HGOBOM	Shortcut to CLEAN with HGOBOM Method
MRC	Shortcut to CLEAN with MX Method
MULTISCALE	Shortcut to CLEAN with MULTISCALE Method
PIPELINE	Pipeline processing of all UV tables
SDI	Shortcut to CLEAN with SDI Method
TIPS	Give Random tip about IMAGER

### 22.2 TIPS

IMAGER\TIPS [Number]

Without argument, print out a random tip about IMAGER.

With an argument, give the corresponding tip number.

### 22.3 PIPELINE

IMAGER\PIPELINE [Arg1 [Arg2]] [/MODE Type] [/WIDGET]

PIPELINE is a command activating the Imaging Pipeline. The pipeline contains all processing steps for high fidelity imaging (Self-calibration, continuum extraction, line identification, etc...)

With no /WIDGET option, PIPELINE run in unattended mode (no SIC\PAUSE statement), one step after the other.

PIPELINE ? will display the Pipeline input parameters

PIPELINE \* will run the whole Pipeline with the current input param

PIPELINE NEXT runs the next following step

PIPELINE LAST will repeat the last step.

PIPELINE with no argument stands for PIPELINE LAST. The /MODE option controls the operating mode (default: last selected mode).

#### 22.3.1 PIPELINE /MODE

IMAGER\PIPELINE [Arg1 [Arg2]] /MODE All|Continuum|Split|Survey

Specify in which mode the Pipeline will run. 4 modes are possible

##### CONTINUUM

Only produce continuum images, no data cube. In this mode, the emission is assumed to be purely continuum, with no significant line contamination.

**SURVEY**

Only produce line+continuum data cubes. No attempt to separate line emission from continuum emission is made. The complete spectral coverage is imaged, at the velocity resolution specified by the user. This mode is especially adapted for extra-galactic work, or sources with lines close to the spectral confusion limit.

**ALL**

Produce data cubes that contains line and continuum emission together. Spectral line identification will be performed if a Catalog is present, with the user-specified velocity range and spectral resolution around each spectral line in the band. If no Catalog is present, the complete spectral coverage is imaged, at the velocity resolution specified by the user.

**SPLIT**

Similar to ALL, but produce data cubes that contains line and continuum emission separately. The separation is based on filtering performed by UV\_PREVIEW.

**22.3.2 PIPELINE /WIDGET****PIPELINE /WIDGET**

Activates the widget that simplifies the interactive control of the Pipeline steps.

Each step is controlled by a separate button. In this mode, the Self-Calibration related button requires user interaction. Some buttons are duplicated on top of the widget, which also contains a SELF-CALIBRATION button that can execute all Self-Calibration related steps in sequence.

The PIPELINE button (as the GO button) will run the full Pipeline without any further user interaction, like the PIPELINE \* command.

**22.3.3 PIPELINE Arguments:**

PIPELINE supports the following arguments when not used in Widget mode, given here in sequential order of actions

```
ORGANIZE
FIND
SELECT
CHECK
```

COMPUTE (or SELF)  
COLLECT  
APPLY  
TIME  
TABLES  
IMAGE  
SHOW  
SAVE

In addition argument SKY can be used to apply primary beam correction to existing images.

#### 22.3.4 ORGANIZE

IMAGER\PIPELINE ORGANIZE

Automatically re-arrange the set of UV tables or UVFITS files in the current directory to a directory tree that is suitable for the Pipeline / Widget use.

This is Step 1, NEXT step is FIND

#### 22.3.5 FIND

IMAGER\PIPELINE FIND

Finds the UV tables in the directory tree and scan their properties for further use

This is Step 2, NEXT step is SELECT

#### 22.3.6 SELECT

IMAGER\PIPELINE SELECT

Select the UV tables to be processed according to the Filter (all%filter) and identify the Wide bands and Narrow bands

This is Step 3, NEXT step is CHECK

#### 22.3.7 CHECK

IMAGER\PIPELINE CHECK

Check whether the continuum is strong enough to require and allow self-calibration.

This is Step 4, NEXT step is COMPUTE (or its alias SELF)

### 22.3.8 COMPUTE

IMAGER\PIPELINE COMPUTE      or      IMAGER\PIPELINE SELF

Compute the Self-calibration solution from the Wide bands UV tables

This is Step 5, NEXT step is COLLECT

### 22.3.9 COLLECT

IMAGER\PIPELINE COLLECT

Improve self-calibration solution by interpolating correction delays between different wide bands. This can increase S/N of self-calibration on weaker sources, but may degrade solutions with very high S/N per band on strong sources.

This is Step 6, NEXT step is APPLY

### 22.3.10 APPLY

IMAGER\PIPELINE APPLY

Apply self-calibration solution derived previously to all Wide and Narrow band UV tables. The selected solution is from the Wide band that is closest in Frequency, using the DELAY mode for the solution.

This is Step 7, NEXT step is TIME

### 22.3.11 TIME

IMAGER\PIPELINE TIME

Time average the self-calibrated UV tables to save space and further time processing

This is Step 8, NEXT step is TABLES

### 22.3.12 TABLES

IMAGER\PIPELINE TABLES

Extract UV tables around each spectral line available in the CATALOG and covered by the frequency setup. Continuum emission is (empirically) separated from Line emission using the UV\_PREVIEW, UV\_BASELINE / UV\_FILTER mechanism.

This step is only needed when direct image analysis in the UV plane is required.

This is Step 9, NEXT step is IMAGE

### 22.3.13 IMAGE

IMAGER\PIPELINE IMAGE

Produce deconvolved images around each spectral line available in the CATALOG and covered by the frequency setup. Continuum emission is (empirically) separated from Line emission using the UV\_PREVIEW, UV\_BASELINE / UV\_FILTER mechanism, and the continuum images are also produced.

This step does not use the result of the PIPELINE TABLES step, but only the self-calibrated UV tables produced by PIPELINE APPLY and PIPELINE TIME.

This is Step 10, NEXT step is SHOW

### 22.3.14 SHOW

IMAGER\PIPELINE SHOW

Show some plots about Self-calibration quality

This is Step 11, NEXT step is SAVE

### 22.3.15 SAVE

IMAGER\PIPELINE SAVE

Save PIPELINE input parameters into ./all-memory.ima, so that PIPELINE \* will redo the whole processing with the these parameters. The script can be edited if any correction is required (e.g. changing image size, robust parameter, etc...)

An implicit SAVE is done after PIPELINE IMAGE

**22.3.16 SKY**

IMAGER\PIPELINE SKY                      Apply primary beam correction to the Clean images in the all%maps (default MAPS) directory to produce the Sky brightness images (.lmv-sky). This steps does nothing when processing Mosaics, since Clean directly restores Sky brightness images for Mosaics.

**22.3.17 NEXT**

IMAGER\PIPELINE NEXT

Run the next step of the Pipeline.

**22.3.18 LAST**

IMAGER\PIPELINE LAST

Repeat the last executed step of the Pipeline (presumably after changing some control parameters)

**22.3.19 Variables**

Apart from the usual imaging parameters, PIPELINE is controlled by a few variables.

ALL%CATALOG	indicates the spectral line catalog (set by the CATALOG comm
ALL%DROP	Number of edge channels drop at each edge
ALL%FILTER	indicates the files to be processed
ALL%MINFRES	is a threshold in spectral resolution to separate continuum-
ALL%RANGE	gives the velocity range and resolution

In addition, the self-calibration step is controlled by ALL%PHASE\_NITER, ALL%PHASE\_TIMES, ALL%AMPLI\_NITER and ALL%AMPLI\_TIMES that specify the number of Clean components and integration times for Phase and Amplitude respectively

**22.3.20 ALL%CATALOG**

Name of spectral line catalog. This is a Read-Only variable, defined using the CATALOG command. See HELP CATALOG for details.

If a line catalog is selected, the Pipeline scripts will produce one image for each spectral line falling into the observed "high resolution" spectral windows, over the specified velocity range ALL%RANGE.

If no line catalog is selected, all channels of all "high resolution" spectral windows will be imaged. No velocity range is used in this case.

"Low resolution" spectral windows will be used to produce continuum only images. The distinction between "Low" and "High" resolution spectral windows is made from variable ALL%MINFRES

### 22.3.21 ALL%DROP

INTEGER ALL%DROP[2]                      This is an integer array giving the number of edge channels ignored when reading a UV table. Edge channels may have different weights than the other ones, especially for ALMA data because of the off-line Doppler correction.

Such low weights edge channels are automatically dropped for Single fields, so you can use ALL%DROP = 0, but not yet for Mosaics, where ALL%DROP = 5 is more appropriate.

### 22.3.22 ALL%FILTER

CHARACTER\*256      ALL%FILTER

File filter to be used to select the relevant UV tables.

This filter MUST NOT contain the .uvt extension. The default filter is \*, but a specific file name can be given to process only one UV table instead of all of them (or all tables for a given source for example).

### 22.3.23 ALL%AMPLI\_NITER

ALL%AMPLI\_NITER is a size-variable integer array of rank 1.

It indicates the number of clean components for each iteration of Amplitude self-calibration. The number of iterations is defined by its number of elements. The size of this array can be changed using the LET /RESIZE option.

0 means to select all Clean components.

### 22.3.24 ALL%AMPLI\_TIMES

ALL%AMPLITIMES is a size-variable real array of rank 1.

It indicates the integration time for each iteration of Phase self-calibration. The number of iterations is defined by its number of elements. The size of this array can be changed using the LET /RESIZE option.

Typical values are 90 to 180 seconds for NOEMA, 60 seconds for ALMA.

### 22.3.25 ALL%COLLECT

Real ALL%COLLECT

Stability Threshold for flagging data after Self-Calibration.

For Self-calibration solutions with more than one iteration, the solution is flagged if the difference between the last two iterations exceeds Threshold times the expected phase error due to noise.

The default is 0, a convention indicating to ignore this flagging step.

When the noise level is appropriately estimated, a Threshold of 3 is a good value to suppress unstable solutions that reflect some issues in the self-calibration model.

### 22.3.26 ALL%COMBINE

Logical ALL%COMBINE

Indicates whether the COLLECT step (that derives an atmospheric delay correction from the per-band phase correction) should be performed or not for the Self-Calibration in PIPELINE mode.

### 22.3.27 ALL%ITIME

Real ALL%ITIME

Integration time used for the TIME compression step. 0 means that IMAGER will derive the best time given the baseline lengths and field of view.

### 22.3.28 ALL%MINFRES

REAL ALL%MINFRES



Maximum frequency resolution under which a UV Table is considered as a spectral line data. UV Tables with coarser spectral resolution are treated as continuum only data: the line emission is filtered out, and a pure continuum image is generated using bandwidth synthesis in this case.

### 22.3.29 ALL%PHASE\_NITER

ALL%PHASE\_NITER is a size-variable integer array of rank 1.

It indicates the number of clean components for each iteration of Phase self-calibration. The number of iterations is defined by its number of elements. The size of this array can be changed using the LET /RESIZE option.

### 22.3.30 ALL%PHASETIMES

ALL%PHASE\_TIMES is a size-variable real array of rank 1.

It indicates the integration time for each iteration of Phase self-calibration. The number of iterations is defined by its number of elements. The size of this array can be changed using the LET /RESIZE option.

Typical values are 45 seconds for NOEMA data, 6 to 24 sec for ALMA data.

### 22.3.31 ALL%RANGE

REAL ALL%RANGE[3]

Velocity sampling around each spectral line (in km/s). ALL%RANGE[1:2] give the Min and Max velocities ([0,0] indicates to take the whole coverage of the sub-band).

ALL%RANGE[3] gives the desired spectral resolution (0 indicates to use the spectral resolution of the sub-band).

### 22.3.32 ALL%SPLIT

LOGICAL ALL%SPLIT

Separate (Split) Line emission from Continuum emission in data Cubes or extracted uv Tables, or keep Line+Continuum data together.

## 22.4 HGOBOM

```
IMAGER\HGOBOM [First Last] [/FLUX Min Max]
```

is a short cut for

```
LET METHOD = HGOBOM  
CLEAN [First Last] [/FLUX Min Max]
```

## 22.5 CLARK

```
IMAGER\CLARK [First Last] [/FLUX Min Max] [
```

is a short cut for

```
LET METHOD = CLARK  
CLEAN [First Last] [/FLUX Min Max]
```

## 22.6 MRC

```
IMAGER\MRC [First Last]
```

is a short cut for

```
LET METHOD = MRC  
CLEAN [First Last]
```

## 22.7 MULTISCALE

```
IMAGER\MULTISCALE [First Last] [/FLUX Min Max]
```

is a short cut for

```
LET METHOD = MULTI  
CLEAN [First Last] [/FLUX Min Max]
```

## 22.8 SDI

```
IMAGER\SDI [First Last] [/FLUX Min Max]
```

is a short cut for

```
LET METHOD = SDI  
CLEAN [First Last] [/FLUX Min Max]
```

## 23 Bugs and Release Notes

This section lists known bugs (or strange features) that are known at the date of release of the documentation, and the list of changes since previous releases. A more complete list is available in the IMAGER Bugs & Release note documentation [here](#) for the PDF version or [there](#) for the Web version

Notes since Documentation release of Version 3.2, dated Jan, 30th, 2022

### 23.1 Recent changes in repository

This section gives the changes made since the last documentation release (as dated above). The changes are available in the working repository, but may not be distributed in any standard Gildas release yet.

- 15-Nov-2022 Add the `/MODE` option to the `PIPELINE` command, with 4 modes: `CONTINUUM`, `SPLIT`, `ALL` or `SURVEY`.
- 14-Nov-2022 Debug use of `MAP_CENTER` variable in various commands (for `Mosaics`, `UV_SELF`, `UV_SHIFT`).
- 08-Nov-2022 Reorganize commands in languages: `EXTRACT`, `SLICE` and `POPUP` are now part of the `DISPLAY\` language
- 05-Sep-2022 Add the `/ASYMMETRIC` option of `MAP_SMOOTH` and `UV_SMOOTH`
- 05-Jul-2022 Add the `MAP_POLAR` command This corresponds to revision 3.4-1 of the Documentation.
- 29-Jun-2022 Ensure `READ` handles properly Random Frequency Axis in UVFITS format
- 29-Jun-2022 Ensure `UV_EXTRACT` works with Random Frequency Axis
- 22-Apr-2022 Improve `UV_PREVIEW` command
- 12-Apr-2022 Support for command `STOKES` on internal buffers.
- 23-Mar-2022 Introduce the `IMAGER\` language, and the `PIPELINE` command. This corresponds to revision 3.3 of the Documentation.

### 23.2 Known Bugs

This section contains the list of bugs known as of June 1, 2023.

- **Discovered** 15-Nov-2022 `UV_RESTORE` in Mosaic mode leads to subsequent crashes if the channel range is restricted by `UV_MAP` because a single beam cannot be applied to all channels.  
This is often the case for ALMA data, because of the shift implied by the Doppler correction when creating the UVFITS files. A work around is to manually drop the edge channels by reading a coherent range of channels, and over-writing the UV data.
- **Corrected** 08-Sep-2022 Bug correction in `EXTRACT` command.
- **Corrected** 29-Jun-2022 `STOKES` command had incorrect derivation from H-V polarization

- **Corrected** 09-Jun-2022 Debug **UV\_FLAG** command - Allow to use without Display.
- **Corrected** 13-Apr-2022 **MAP\_COMBINE** and **COMBINE** were not supporting big files.
- **Corrected** 12-Apr-2022 **UV\_RESIDUAL** was not working on a non-sorted Mosaic data set. This could only happen by reading the Clean Component Table after reading the UV data, without any imaging step.
- **Corrected** 09-Mar-2022 **CCT\_MERGE** Concatenation was improper
- **Corrected** 07-Mar-2022 Beam size derivation was incorrect when an **ANGLE** was specified
- **Corrected** 08-Feb-2022 **UV\_RESTORE** was not using fixed beam size.
- **Corrected** 18-Jan-2022 **SINGLEDISH** data was incorrectly read, probably since 20-Sep-2021 (v1.53 of read.f90). Improper values were thus used by the **UV\_SHORT** command (**Discovered** 17-Jan-2022 only).
- **Corrected** 12-Jan-2022 Mosaic offsets were improperly computed by command **UV\_FIELDS** since 29-Jul-2021 (bug reported 10-Jan-2022). The script @ **fits\_to\_uvt** was thus leading to wrong pointing offsets.
- **Corrected** 10-Jan-2022 A improper interaction between scripts was causing strange behaviour when switching between **EXPLORE** and **INSPECT\_3D** commands.
- **Corrected** 06-Jan-2022 The **SIC** command **DEFINE IMAGE** failed on large FITS files. This prevented **SHOW** and **VIEW** to work directly from these files.
- **Corrected** 18-Dec-2021 **UV\_TIME** produced incorrect results on tables with different weights per channel (e.g. those produced by **UV\_MERGE /MODE CONCATENATE**).
- **Corrected** 13-Dec-2021 Remove occasional infinite loop in **MAP\_CONTINUUM** with method **GAUSS** (discovered 01-Dec-2021)
- **Corrected** 18-Nov-2021 **UV\_REWEIGHT** syntax bug

### 23.3 Functional changes from previous versions

#### Changes in Version 3.3

- 23-Mar-2022 Introduce the **IMAGER\** language. Implement the **PIPELINE** command there, and some miscellaneous (previously user-defined) commands like **TIPS** and **POPUP**

#### Changes in Version 3.2

- 18-Mar-2022 Add the **CLEAN /RESTART** capability
- 10-Mar-2022 Improve dirty beam related commands behaviour: replace **MAP\_BEAM\_STEP** by **BEAM\_STEP**, use **BEAM\_SIZE** to specify beam shape.
- 07-Mar-2022 Allow **WRITE BEAM /APPEND** in all cases
- 08-Feb-2022 Implement the **CLEAN\_STOP** syntax in **CLEAN**
- 10-Jan-2022 Implement the **LOAD** command in **VIEWER**.

- 07-Jan-2022 Implement **SHOWPV** and improve transposed data display.
- 06-Jan-2022 Allow direct **READ** of FITS data cubes.
- 03-Jan-2022 Improve syntax of **COMBINE**
- 17-Dec-2021 Improve **UV\_CHECK BEAM** and **FIT** commands.
- 16-Dec-2021 Add the **UV\_MERGE /MODE CONCATENATE** command to stitch adjacent or overlapping spectral windows. Imaging is in general only possible using **BEAM\_STEP = 1** after this, so far.
- 13-Dec-2021 Implement a fast, reliable version of "statcont" through the **MAP\_CONTINUUM** command (run time < 40 secs for a 28 Gbyte data set on a 64-core machine)
- 13-Dec-2021 Globally revised the Robust weighting scheme. Speed up by huge amount for large ( $\geq 10$  MegaVis) number of visibilities. UV data sorting not required anymore.
- 08-Dec-2021 Change the CASA - GILDAS interface. Use pure-Python scripts and put them in the **\$HOME/.casa** directory to have a CASA-version independent solution.
- 07-Dec-2021 A missing initialization was causing **UV\_RESTORE** to use the slow mode on some compiler versions.
- 06-Dec-2021 Speed up (by a factor 5-10) the Natural weighting scheme when there is only 1 channel.
- 19-Nov-2021 Create the **VIEWER** program, that only contains the **DISPLAY\** language.
- 19-Nov-2021 Expand the **COMMAND ? Key** mechanism to many commands.
- 18-Nov-2021 Add the **STATISTIC /UPDATE** and **FIT /JVM\_FACTOR** commands

## A IMAGER versus CASA

### A.1 Imaging Philosophy and Data Architecture

CASA intends to solve the *Measurement Equation*, whatever the complexity of this process. It is a all-in-one package for this purpose, where calibration and imaging are deeply intermixed and use a unified data format. As a result, a CASA Measurement Set is a complex architecture encompassing relations between many components stored as Tables in a directory-like tree. It can handle calibrated data, calibration tables, multisource data sets, raw data and final images in the same architecture, allowing to retain all information to process complex images, such as multi-frequency synthesis of polarized emission observed in a mosaic of fields.

On the contrary, GILDAS is designed to break the process in totally independent steps. For IRAM data, calibration is done in one program (CLIC for interferometry with NOEMA or CLASS for single-dish with the 30-m), and imaging in another (here **IMAGER**), with a clear intermediate step to change from the calibration data format (using the CLASSIC container) to UV Tables or CLASS Tables. In particular, **IMAGER** does not handle polarization transparently at the current time: polarization states must be imaged independently. The Gildas Data Format stores a limited number of informations in a single binary data file with a compact binary header, and is only suited for calibrated data. UV Tables are little more elaborate than simple images, but still limited in complexity.

### A.2 Frequency and Velocity scales

In the ALMA use of CASA, all observations are kept in the Observatory frequency frame, and only converted to a celestial reference frame (such as the Local Standard of Rest, LSRK) at later stages, during imaging if requested.

GILDAS is more analysis oriented, and contains a dual interpretation of the frequency axis. This axis can either be interpreted with a Velocity scale, usually in the LSRK frame relative to a spectral line rest frequency, or as a Rest Frequency, with the astronomical source velocity specified. The choice of representation depends on the astronomer's science objective: astronomical object study (in which case the Velocity representation is more appropriate) or chemical composition study (in which case the Rest Frequency representation is preferred).

### A.3 Transferring UV data from CASA

The basic idea of data transfer at this stage is to transfer a whole spectral window to GILDAS, and use the simpler and faster tools available in **IMAGER** for extracting channels, resampling, subtracting continuum, etc... rather than doing that in CASA.

### A.4 In CASA

The steps in CASA involve

1. Separating spectral windows and different sources into independent (temporary) MS
2. Getting rid of flagged data
3. Setting the velocity reference frame and correcting for Doppler motions
4. Exporting to UVFITS

## 5. Removing the intermediate MS

The intermediate MS is created using *mstransform*, with `keepflags=False`, `regridms=True`, `outframe='LSRK'`. Source and spectral window identification is done using keywords `spw` and `field`, and an appropriate rest frequency is specified (in MHz) using `restfreq`. Finally, *exportuvfits* is used on the simple intermediate MS. **IMAGER** provides to CASA a tool named *casagildas()* that scans the content of the Measurement Set (using *listobs()* to automatically do this on all combinations of spectral windows and sources).

### A.5 In **IMAGER**

The script `@ fits_to_uv` handles the conversion from UVFITS to *uv* table format. The steps in GILDAS involve

1. Converting UVFITS to UVT
2. Collapsing the polarization information
3. Adjusting the weights to properly estimate the noise
4. Identify and flag bad data
5. Setting the frequency and velocity references

It also handles some nasty details, like the source coordinates being hidden in different places depending on the CASA version.

- Step 1  
`fits 'name'.uvfits to 'name'.uvt`  
 will create a GILDAS UV table from the UVFITS file. The signal is assumed to be unpolarized at this stage. With the `/STOKES` option, polarization information would be carried on properly at this stage.
- Step 2 This step is only needed with the `/STOKES` option. It could be done manually by using command **STOKES** that handles Stokes parameter conversion. The desired polarization state should be set to `NONE` to optimize signal to noise ratio for unpolarized sources, to `I` if polarization is a concern.
- Step 3 This step is only carried on if the `/WEIGHT` option is present. Depending on CASA version, the weights are not handled in the same way. In Casa 3.4, they are approximately correct. In Casa 4.1, they are off by a large factor (perhaps the number of channels...). Task `uv_noise` utilizes the many channels available (3840 per spectral baseband in FDM mode) to compute a statistic per visibility, and adjust the weight through a median scaling factor. Task `uv_noise` will also flag data with “unusual” weights (deviating from the median by more than some factor (user specified, default 3)).
- Step 4 Task `uv_trim` will remove the flagged data from the UV table, saving space.
- In practice, the optional Steps 2 to 4 are handled by a single task called `uv_casa`, which saves 2 intermediate files (and thus 2 reads and 2 writes of large files).

- Step 5

At this stage, one could start usual imaging using the standard imaging commands `READ UV 'name'; UV_MAP`. Commands `SPECIFY FREQUENCY Value` and `SPECIFY VELOCITY Value` will set the desired correspondence between Velocity and Frequency axis.

## A.6 Transferring Image data

In the Quality Assessment step 2 (QA2), the ALMA ARC staff usually provides one or more deconvolved images as FITS files. These FITS files can readily be converted into GILDAS images with the `SIC` command `FITS:`

`FITS 'name'.fits TO 'name'.gdf`

They will however have a frequency axis labelled in `FREQUENCY`, while GILDAS usually works with this axis labelled in `VELOCITY`. They can also be accessed as `SIC` Image variables using command `DEFINE IMAGE`

In `IMAGER`, direct display of these FITS files is normally possible with commands `SHOW` and `VIEW`, or other `DISPLAY\` commands.

## B Properties of the Fourier Transform

Let us name  $f(x)$  a function, and  $F(X)$  its Fourier transform. We use here the simple, non-unitary convention

- Definition:  $F(X) = \int_{-\infty}^{+\infty} f(x) e^{-2i\pi x X} dx$
- Linearity:  $h(x) = af(x) + bg(x)$ , then  $H(X) = aF(X) + bG(X)$
- Translation:  $h(x) = f(x - x_0)$ , then  $H(X) = e^{-2i\pi x_0 X} F(X)$
- Shifting:  $h(x) = e^{2i\pi x X_0} f(x)$ , then  $H(X) = F(X - X_0)$
- Scaling:  $h(x) = f(ax)$ , then  $H(X) = \frac{1}{|a|} F(\frac{X}{a})$  (the so-called *time reversal* property is obtained with  $a = 1$ )
- Conjugation: if  $h(x) = \bar{f}(x)$ , then  $H(X) = \bar{F}(-X)$
- Integration: With  $X = 0$  in the definition  

$$F(0) = \int_{-\infty}^{+\infty} f(x) dx$$
- Convolution:  $h(x) = f(x) * g(x)$  then  $H(X) = F(X)G(X)$ .  
The Fourier Transform of a product of two functions is the convolution of the Fourier Transforms of the functions.
- Uncertainty principle: the more concentrated  $f(x)$  is, the more spread out its Fourier transform  $F(X)$  must be. In particular, the scaling property of the Fourier transform may be seen as saying: if we squeeze a function in  $x$ , its Fourier transform stretches out in  $X$ . It is not possible to arbitrarily concentrate both a function and its Fourier transform.

The definition, illustrated here with scalars, also holds for  $x, X$  being 2-D vectors in Euclidean space, the product in the definition being a standard dot product of these vectors.



## C Revision History

This section contains a verbatim revision history taken from the **IMAGER** code. Except for minor typos or cosmetic changes, each modification in the code is documented by 1 line of code that includes three informations:

- The language revision number of the affected command
- the date of the revision
- a short description of the change

**IMAGER** lists the revision numbers of all its languages at start of the program. This information can be useful for users encountering a suspected bug or strange behaviour, allowing him/her to see whether the problem has been handled since the version of **IMAGER** they use.

### C.1 DISPLAY Language

### C.2 CLEAN Language

### C.3 ADVANCED Language

### C.4 CALIBRATE Language

### C.5 BUNDLES Language

### C.6 IMAGER Language

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