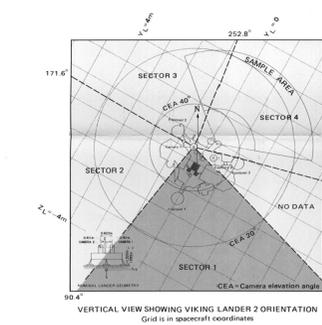


DIFFERENTIAL DATA FOR POINTS IN SCENE

Point No.	Name	Upl. Sample No.	Upl. Elevation	Upl. Azimuth
1	Point 1	114	20	140
2	Point 2	114	20	140
3	Point 3	114	20	140
4	Point 4	114	20	140
5	Point 5	114	20	140
6	Point 6	114	20	140
7	Point 7	114	20	140
8	Point 8	114	20	140
9	Point 9	114	20	140
10	Point 10	114	20	140
11	Point 11	114	20	140
12	Point 12	114	20	140
13	Point 13	114	20	140
14	Point 14	114	20	140
15	Point 15	114	20	140
16	Point 16	114	20	140
17	Point 17	114	20	140
18	Point 18	114	20	140
19	Point 19	114	20	140
20	Point 20	114	20	140



**DESCRIPTION OF SCENE**  
This view is to the south over the top of the lander. The surface is littered with large irregularly broken and pitted blocks. A few blocks have smooth conchoidal fractures (line 220, sample 1150), typical of glassy to fine-grained volcanic rocks.

At the right center is the tubular mast of the high gain S-band antenna (line 150, sample 1940) that was used to communicate directly with Earth. The bright objects on each side of the mast are covers over the Radiometer Thermoelectric Generators (RTG) (line 400, sample 2150, line 200, sample 900). Other parts of the lander visible in the scene are: calibration charts for the cameras (line 350, sample 930; line 550, sample 1400); VHF-relay antenna (line 320, sample 1050); and sensorimeter (line 450, sample 1200).

**THE VIKING MISSION**  
Two Viking spacecraft, each consisting of an orbiter and lander, were launched from Kennedy Space Center on August 20 and September 9, 1975. The Viking 1 spacecraft arrived at Mars on June 19, 1976, and was placed in a highly elliptic orbit around the planet at a perihelion altitude of nearly 1500 km. The orbiter camera was used in conjunction with other instruments to find a suitable landing site for the lander. After about 30 days in orbit, the lander was separated from the orbiter, and on July 20, 1976, Viking Lander 1 touched down on the surface of Mars at 0° 22'43" N, 108° 02' 47.86" W (Waring and Jones, 1980) on the west edge of a large basin called Chryse Planitia. It landed in a rubble position at a 3° tilt downward in the direction 284.9° clockwise from north.

The side of the lander on which the two cameras are mounted faces southeast. When the cameras are pointed in a direction normal to the front of the lander, the viewing direction is 141.6° clockwise from north along the horizon. The first picture from the surface of Mars, of an area near the lander's footpad 3, was taken immediately after landing by camera 2. During the ensuing 45 days, the camera responded to all commands and successfully carried out their assigned mission. On September 2, the activities of Lander 1 were resumed to accommodate the planned receipt of data from Viking Lander 2.

On September 3, 1976, Viking Lander 2 successfully landed on Utopia Planitia at Mars (47°56' N, 225°35' W), more than 6500 km northeast of Lander 1 (Mayo and others, 1977; Davies and others, 1978). Lander 2 faces approximately north and tilts 8.2° downward in the direction of 277.4° clockwise from north. The viewing direction of its camera when pointed in a direction normal to the front of the lander is 29.0° clockwise from north along the horizon. The cameras on Viking Lander 2 operated successfully for 61 days until the primary mission of both landers was completed on November 15, 1976, at solar conjunction.

During the primary mission, 454 pictures of the martian surface were processed from Viking Lander 1 data and 482 pictures from Viking Lander 2 data. The extended mission of Viking began December 15, after solar conjunction, and ended in June 1978. During this period, an additional 1546 pictures were obtained from Lander 1 data and 1311 pictures from Lander 2 data. A comprehensive description of the Viking primary mission and the results of eight scientific experiments on board the landers were published in the Journal of Geophysical Research (v. 82, no. 28, Sept. 30, 1977; see References).

\*Latitudes are geographic (see de Vaucouleurs and others, 1973).

**VIKING LANDER MOSAICS**  
The Viking Lander camera acquired many high-resolution pictures of the Chryse Planitia and Utopia Planitia landing sites. Each picture is the product of computer processing on Earth of digital-image data transmitted from Mars as a result of "camera events" carried out by one of the lander camera systems. Further computer processing of data from a selected number of these events yielded a total of 10 mosaics. Two pairs of mosaics from Lander 1 data (one mosaic from each camera) consisted of one pair made from data taken in the morning (0700-0800 hours) and one pair made with data acquired in mid-afternoon (1400-1530 hours). Similarly, three pairs of mosaics for the Lander 2 site consisted of one pair between 1700 and 1800 hours, one pair at noon, and one pair between 1700 and 1800 hours.

Procedures used for processing the Viking Lander camera data were described by Lovelish and others (1977). The individual camera events used in each mosaic are identified in the outline of the accompanying camera view. Detailed description and reproductions of these camera events were given by Tucker (1978). Copies of the Viking Lander pictures can be obtained from the National Space Science Data Center, Goddard Space Flight Center, Greenbelt, MD, 20771.

The Lander camera system (Huck and others, 1975a) has selectable focus settings for a depth of field from 1.2 m to infinity in the high-resolution (0.04° instantaneous field of view) mode. The survey (low-resolution) mode has an instantaneous field of view of 0.12°, this mode was used in the mosaics only where no high-resolution data were acquired. Each complete mosaic extends 342.5° in azimuth, from approximately 5° above the horizon to 60° below. A complete mosaic incorporates approximately 15 million picture elements (pixels). In order to manage the processing of such large data bases, each mosaic was compiled from four individual azimuthal sectors.

Most of the data used in the mosaics were selected from the primary mission. In some cases, extended-mission data were included where primary-mission coverage was absent or where the surface was obscured by the sampler arms. Further selection was made on the basis of optimum focus.

The image data were photometrically corrected (Huck and others, 1975b; Patterson and others, 1977; Wolfe and others, 1977) for differences caused by variations in exposure and for solar-lighting differences caused by minor time-of-day variations in the pictures of the set. The geometry was then transformed to a local Mars horizon and corrected for perspective camera errors (Patterson and others, 1977; Wolfe, 1981). The corrected pixels comprising a sector were then combined by the computer into a single image, and an optimum contrast correction was applied.

The mosaics are composites of the best pixels of all the Lander pictures used for each sector. In the computer mosaicking process, the image data derived from the camera events for each sector were assigned positions on the basis of equality or detail. These data were examined by the computer in sequence according to the priorities, and the best pixels of each data set were used for the mosaic.

The computer formatting of the Viking Lander mosaics was done at the Image Processing Laboratory of the Jet Propulsion Laboratory of the California Institute of Technology, Pasadena, Calif., under the general supervision of Elliott C. Levintahl of the Department of Genetics, Stanford University, who represented the Viking Lander Imaging Team. A detailed description of the multiple steps involved in the construction of the Viking Lander mosaics and an acknowledgment of the many people who assisted in the project were given by Lovelish (1980).

**GEOMETRY OF THE MOSAICS**  
The cameras on the Viking Lander acquire data by sampling in equal increments of elevation and azimuth angle. In the accompanying mosaic, 8 mm subtends a 1° horizontal or vertical angle, regardless of the place of measurement within the panorama. If the martian surface were flat, one pixel (0.04°) on the surface would be 1 m wide at 60° camera elevation and 2 m wide at the horizon 3 km away. Characteristically for this type of imaging system, most straight lines in the scene appear curved in the reconstruction. This representation of the picture data differs from that of a com-

ventional camera having "point perspective" picture geometry, in which rays are projected from object space, through the perspective point in the camera lens, to an image plane in the camera.

The geometry of the Lander pictures is complicated by additional factors. Because both landers are tilted with respect to the horizon, on the uncorrected pictures the horizon resembles a sine curve. Computer rectification of the pictures results in a straight horizon along which vertical angles can be measured with respect to the local gravity vector, and horizontal angles can be measured from martian north. These angles are not related in any simple way to the azimuth and elevation angles given in "camera coordinates" for the uncorrected pictures.

There are other geometric distortions due to the camera: optic path distortion that affects a light ray after it passes the camera window; and camera-system distortions, or "bulb-down" errors, that are caused by the way the cameras are mounted on the lander. The geometric transformation used in creating the mosaics took into account the optic path distortion but not the "bulb-down" errors. However, along the horizon, the error in azimuth angle is equal to the rotational "bulb-down" error for each camera to an accuracy of less than 1 pixel. The scale "azimuth angles from Mars north" has been adjusted to take into account this correction.

The residual azimuth angle errors are less than 1 pixel along the horizon and become larger with steeper elevation angles and large lander tilts. For the worst case, Lander 2, camera 1, this error is a maximum of 5.7 ± 1 pixels at 60° elevation. The somewhat sinusoidal azimuth-dependent elevation error is a maximum of 1.3 ± 1 pixels for Lander 2, camera 1, and approximately 1 pixel for the other cameras.

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