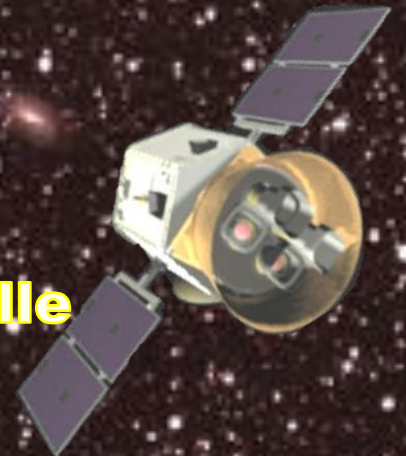
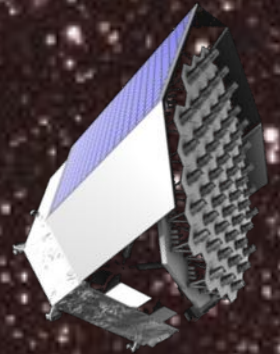
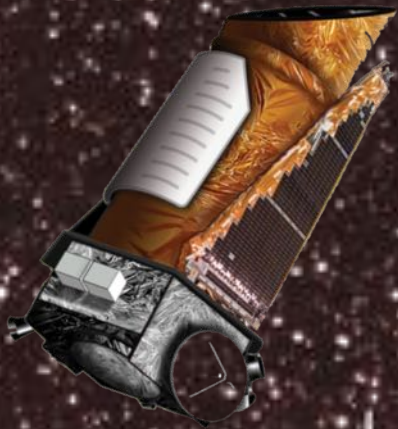


# ***The Impact of Stellar Variability on the Detection of Transiting Earth-like Planets***

**Jon M. Jenkins  
NASA Ames Research Center**

**Wednesday October 24 2018**

**Institute for Planetary Science  
Laboratoire d'Astrophysique de Marseille  
Marseille, France**





# Overview



*A Search for Earth-size  
Planets*

- **The Science Operations Center Pipeline**
- **Solar Variability**
- **Detection Theory**
- **A Wavelet-based Adaptive Matched Filter**
- **Observations of Stellar Noise on Transit Timescales**
- **Excess Stellar Variability**
- **Summary**



# KEPLER

SCIENCE DATA PROCESSING PIPELINE

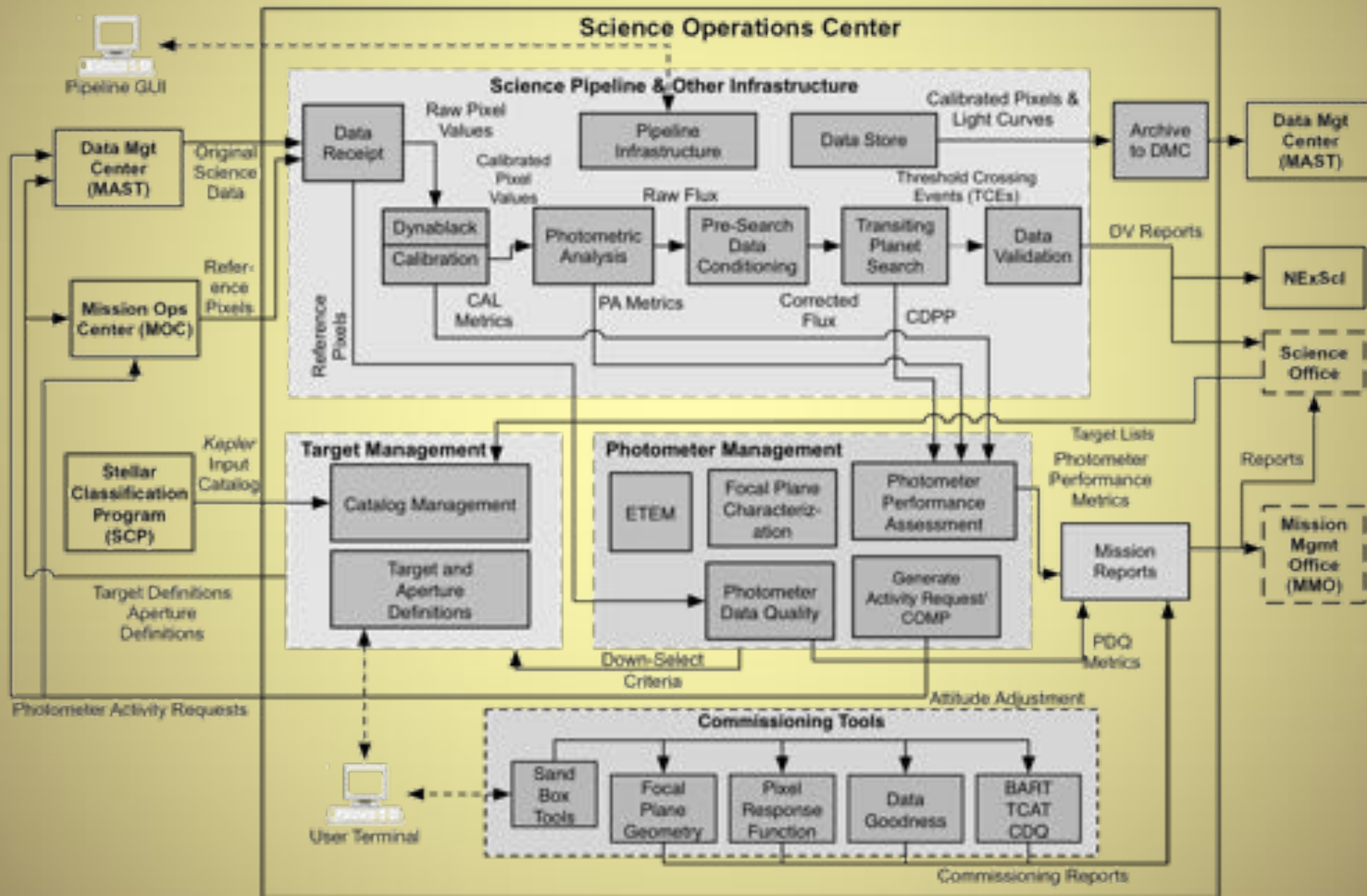




# Science Operations Center Architecture

*Kepler*

A Search for Earth-size Planets

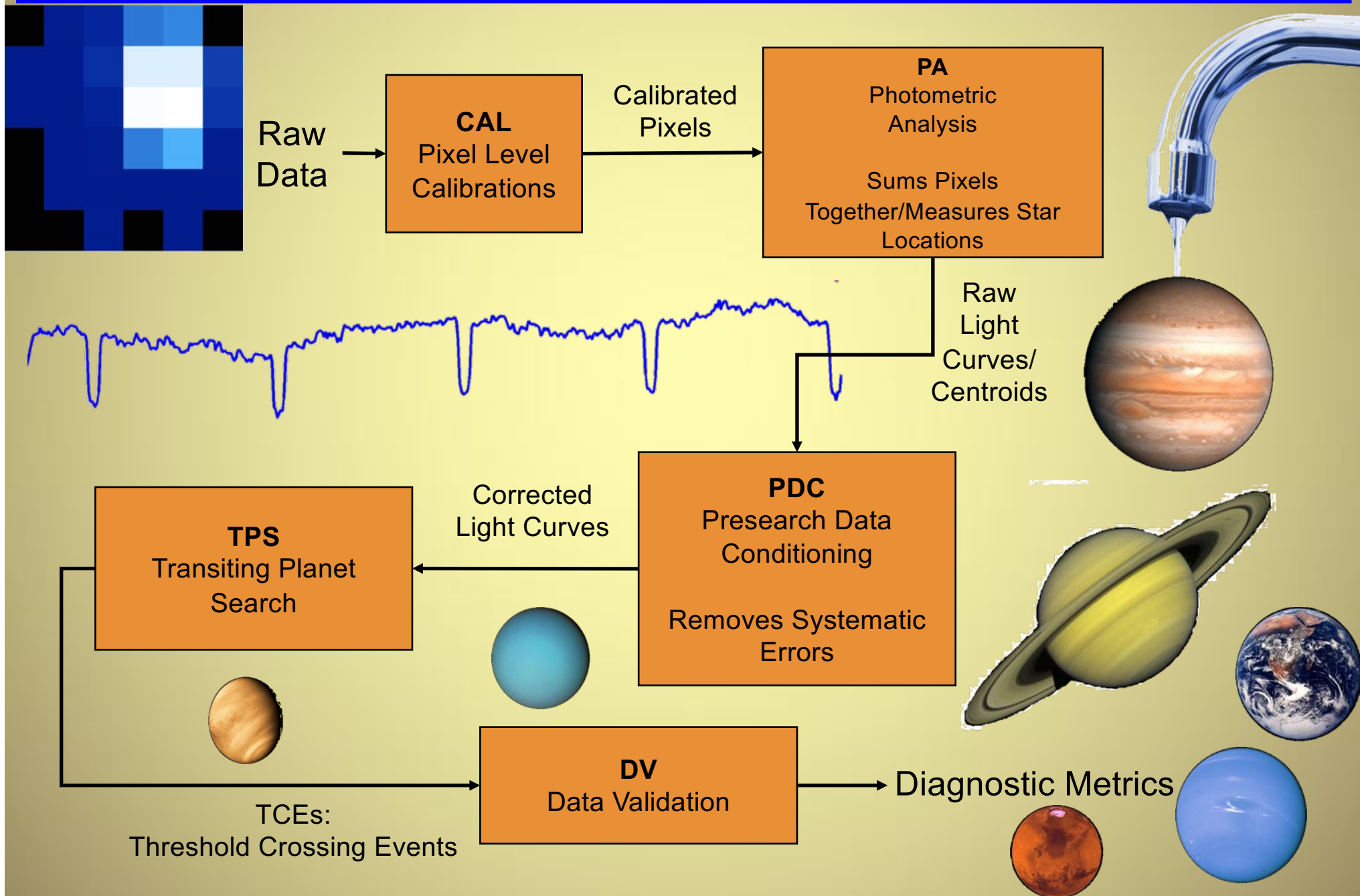


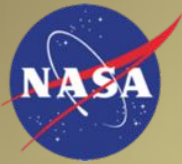


# The Kepler Science Pipeline: From Pixels To Planets

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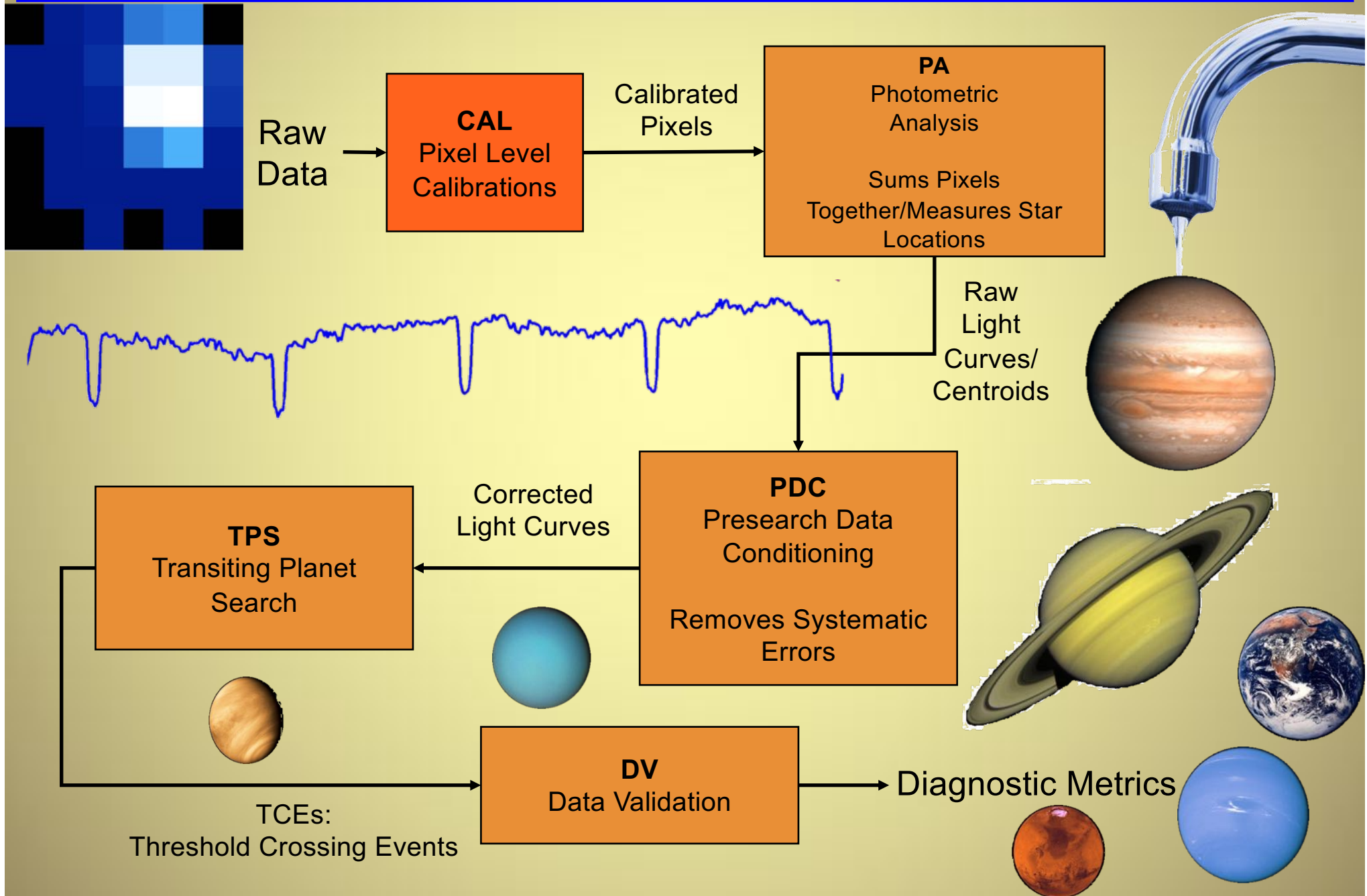
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Planets*





# The Kepler Science Pipeline: From Pixels To Planets

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A Search for Earth-size  
Planets

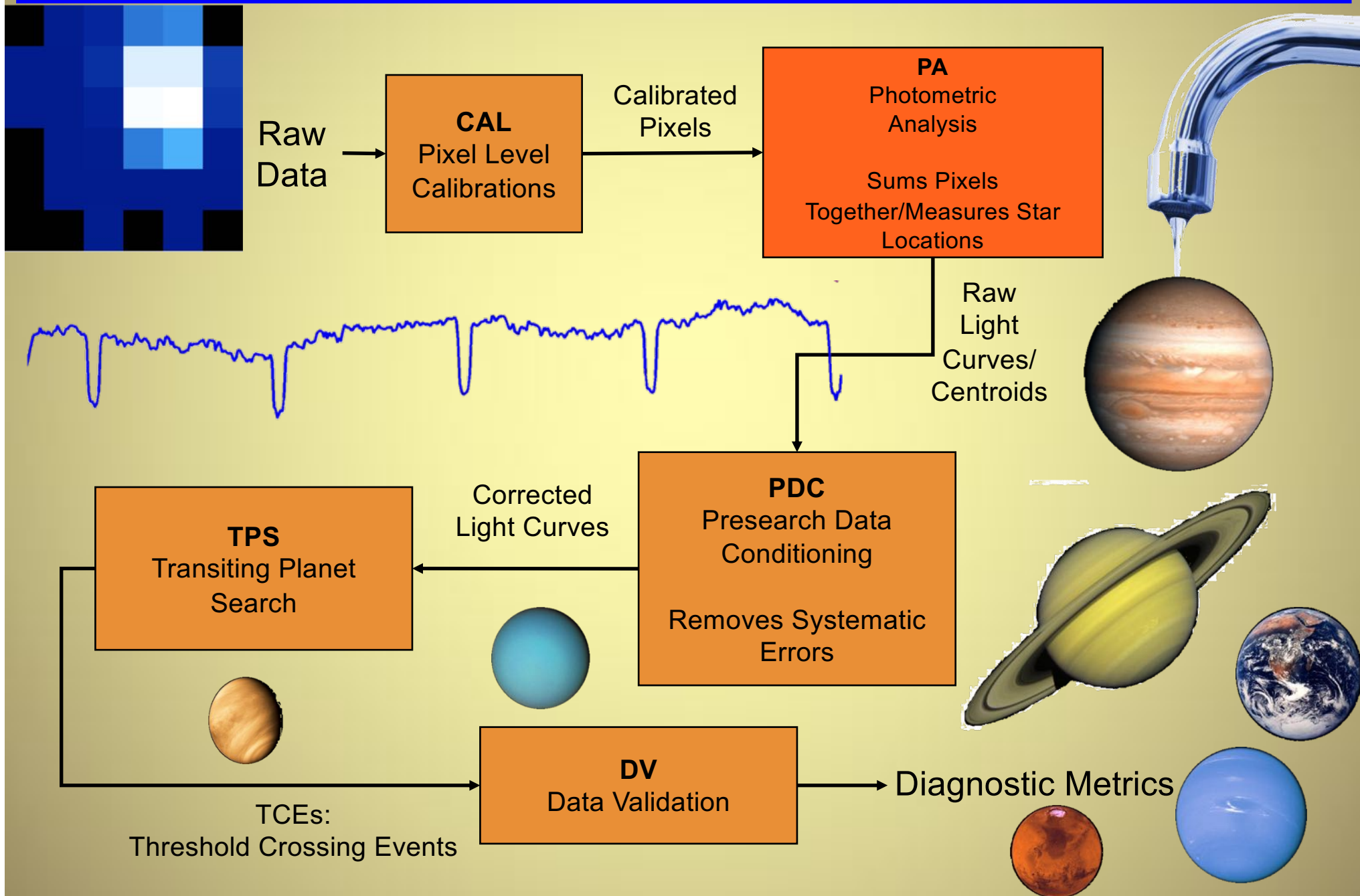


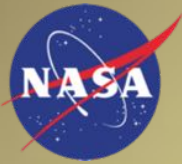


# The Kepler Science Pipeline: From Pixels To Planets

*Kepler*

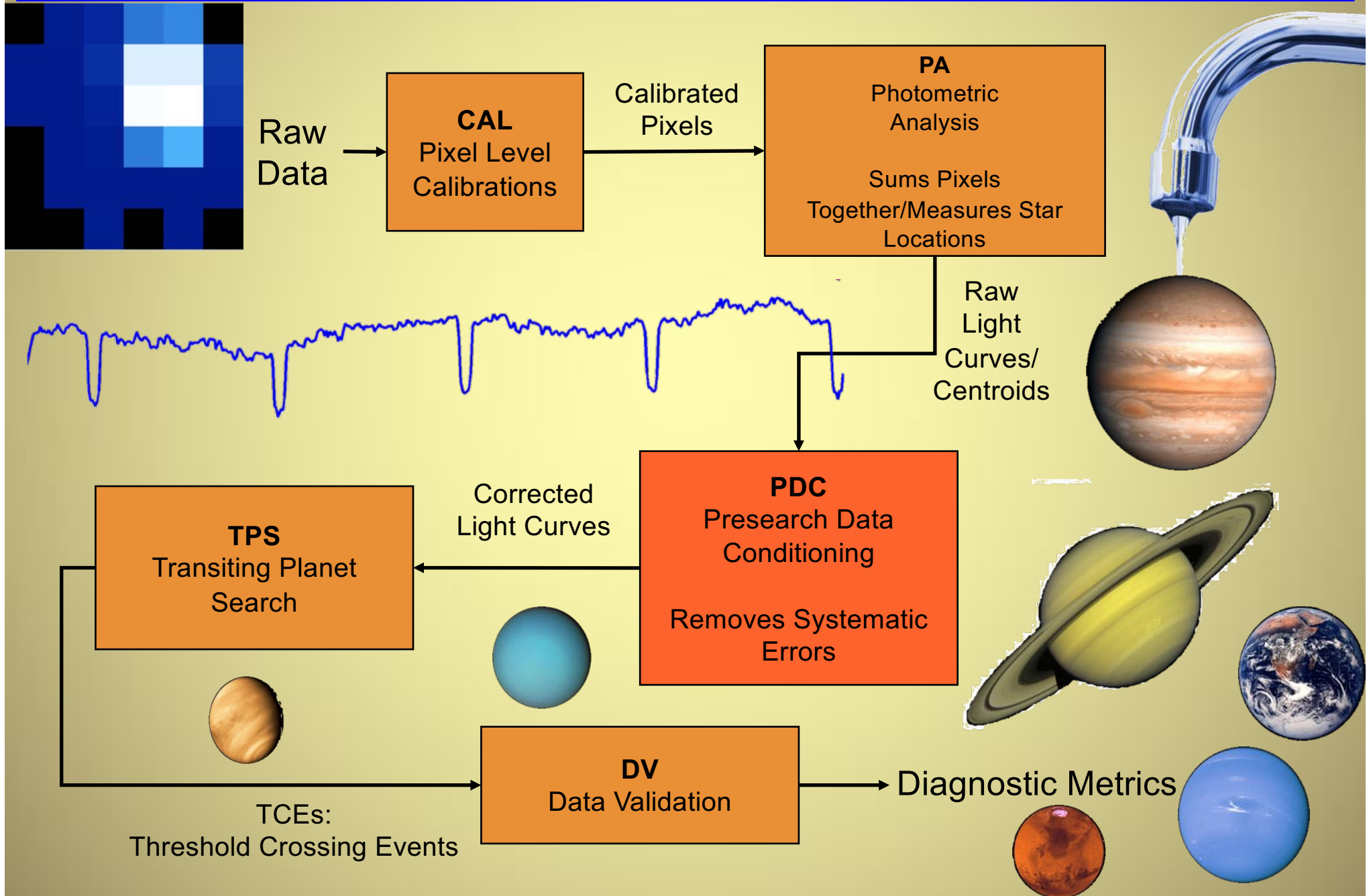
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# The Kepler Science Pipeline: From Pixels To Planets

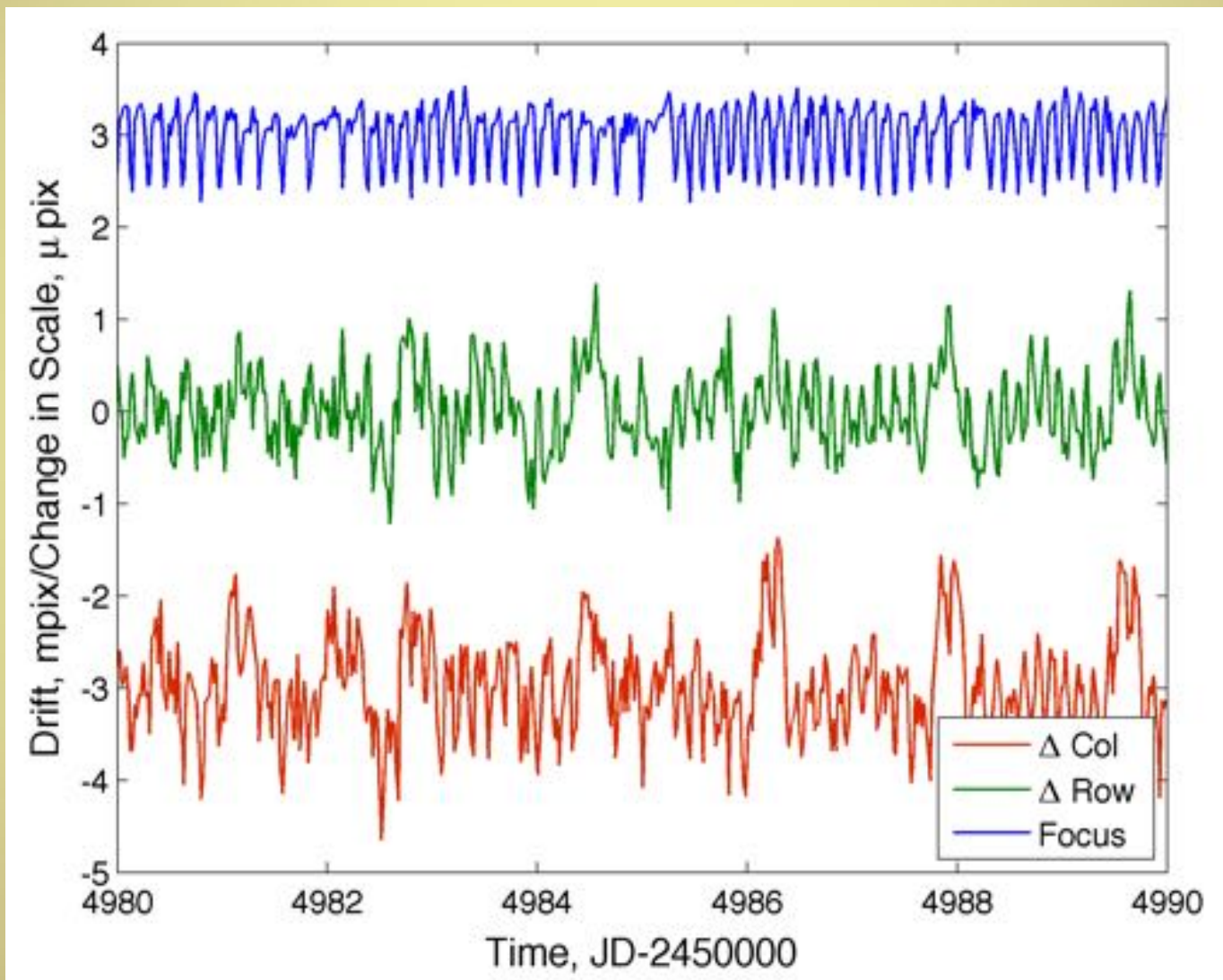
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# Short Timescale Instrumental Errors

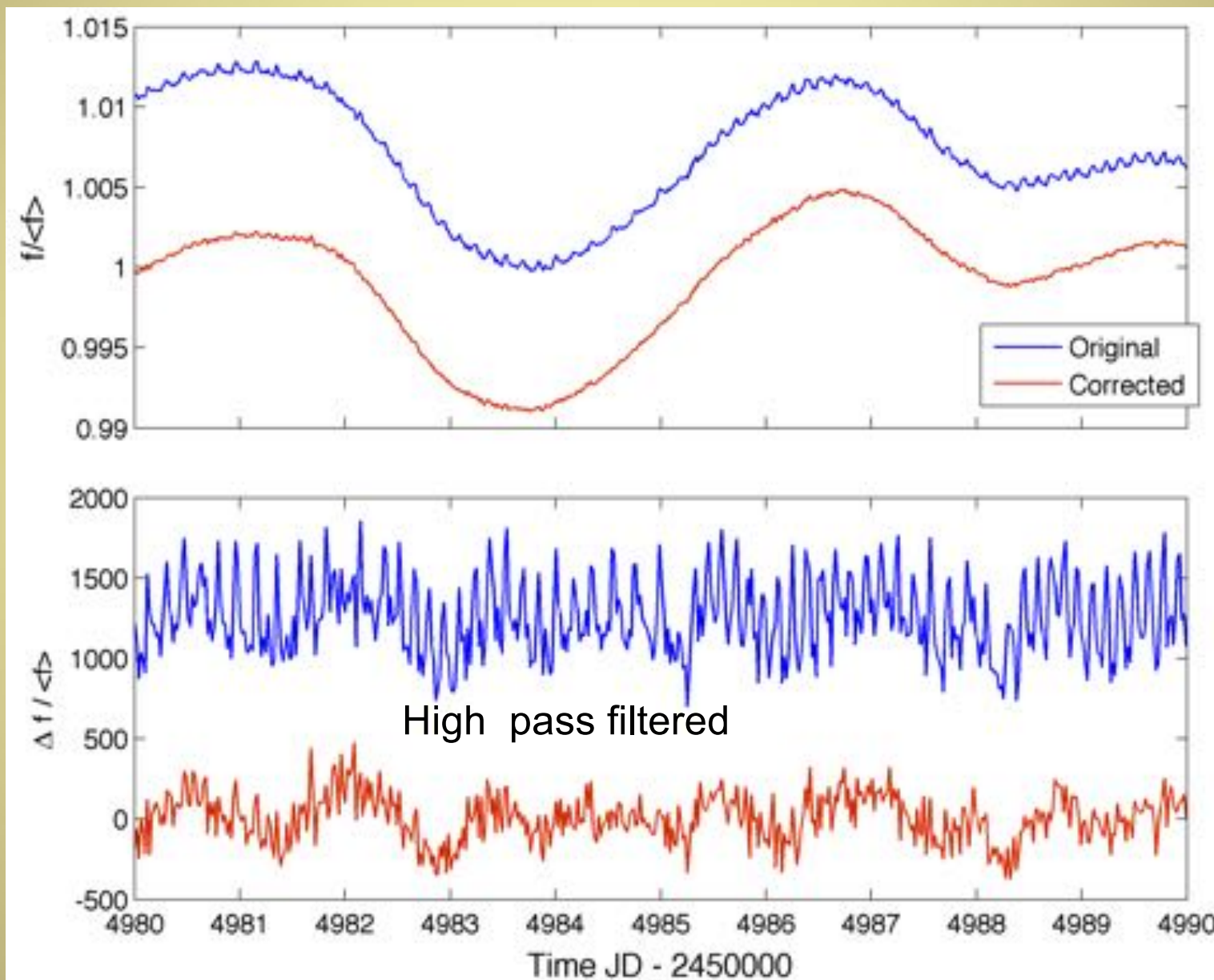
Signature of a heater cycling on the reaction wheels 3/4



*Kepler* is sensitive to its thermal environment

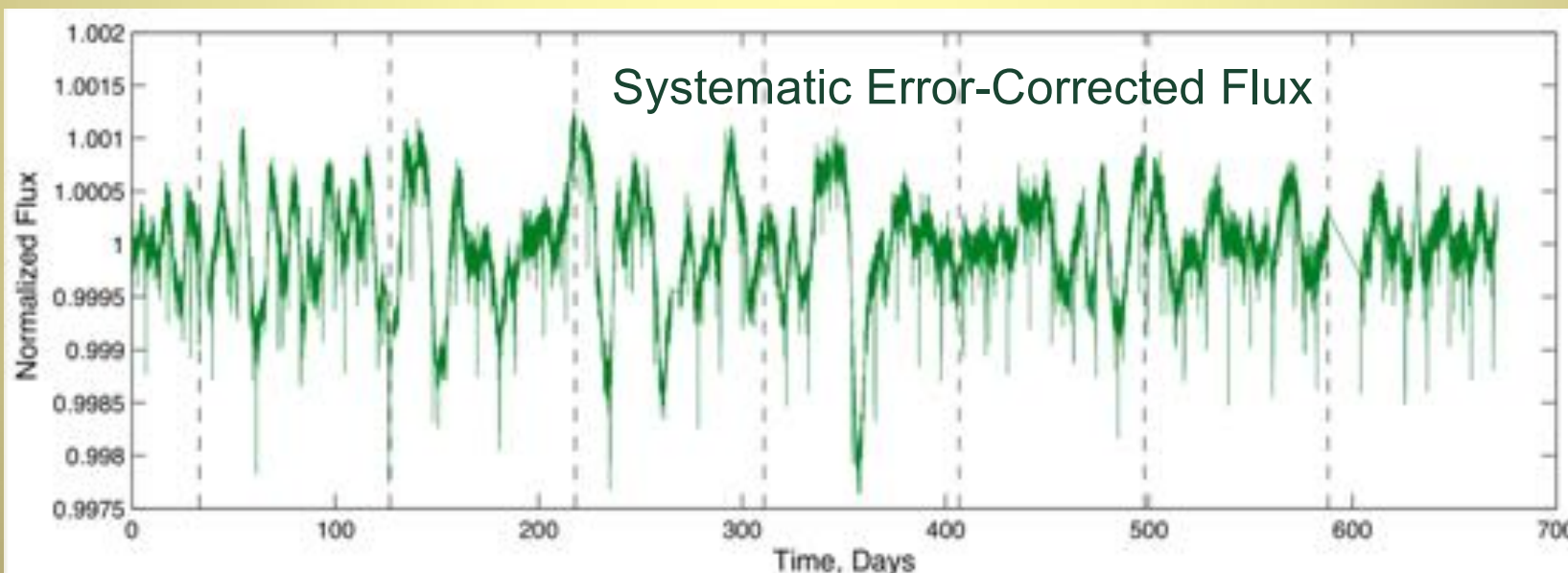
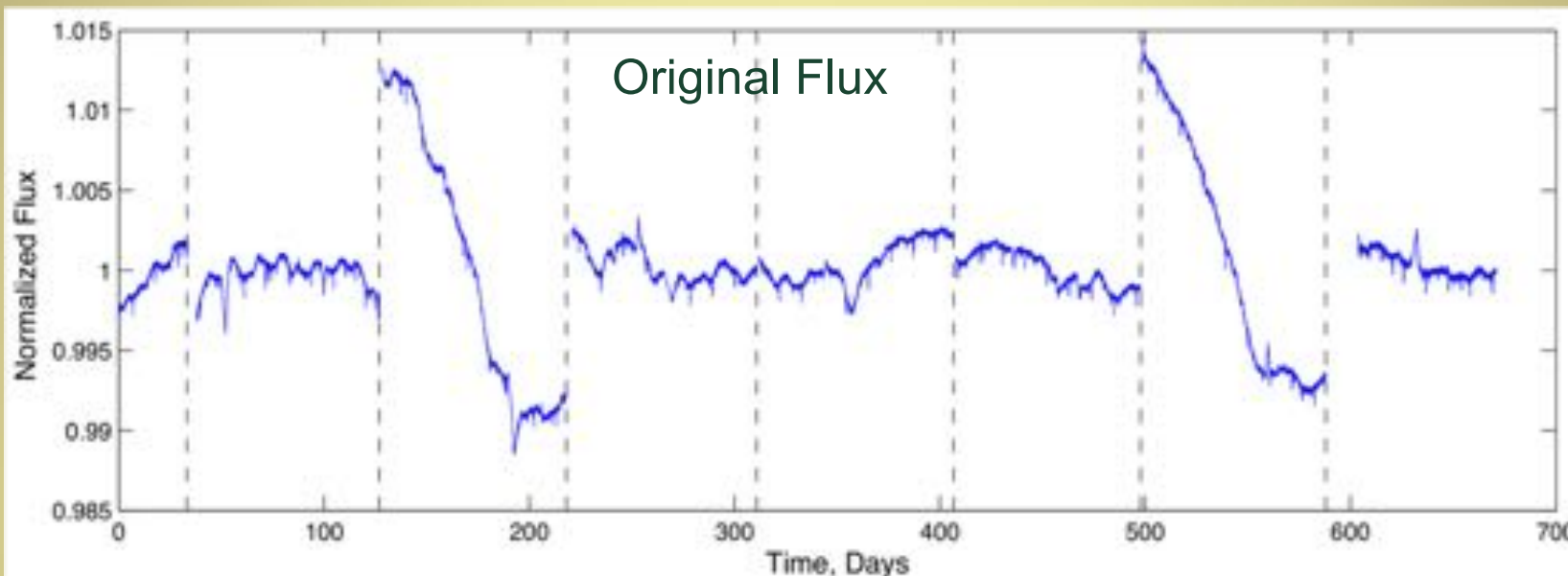


# Instrumental Effects in Photometry

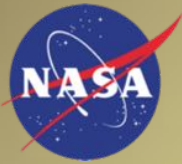




# Correcting Systematic Errors

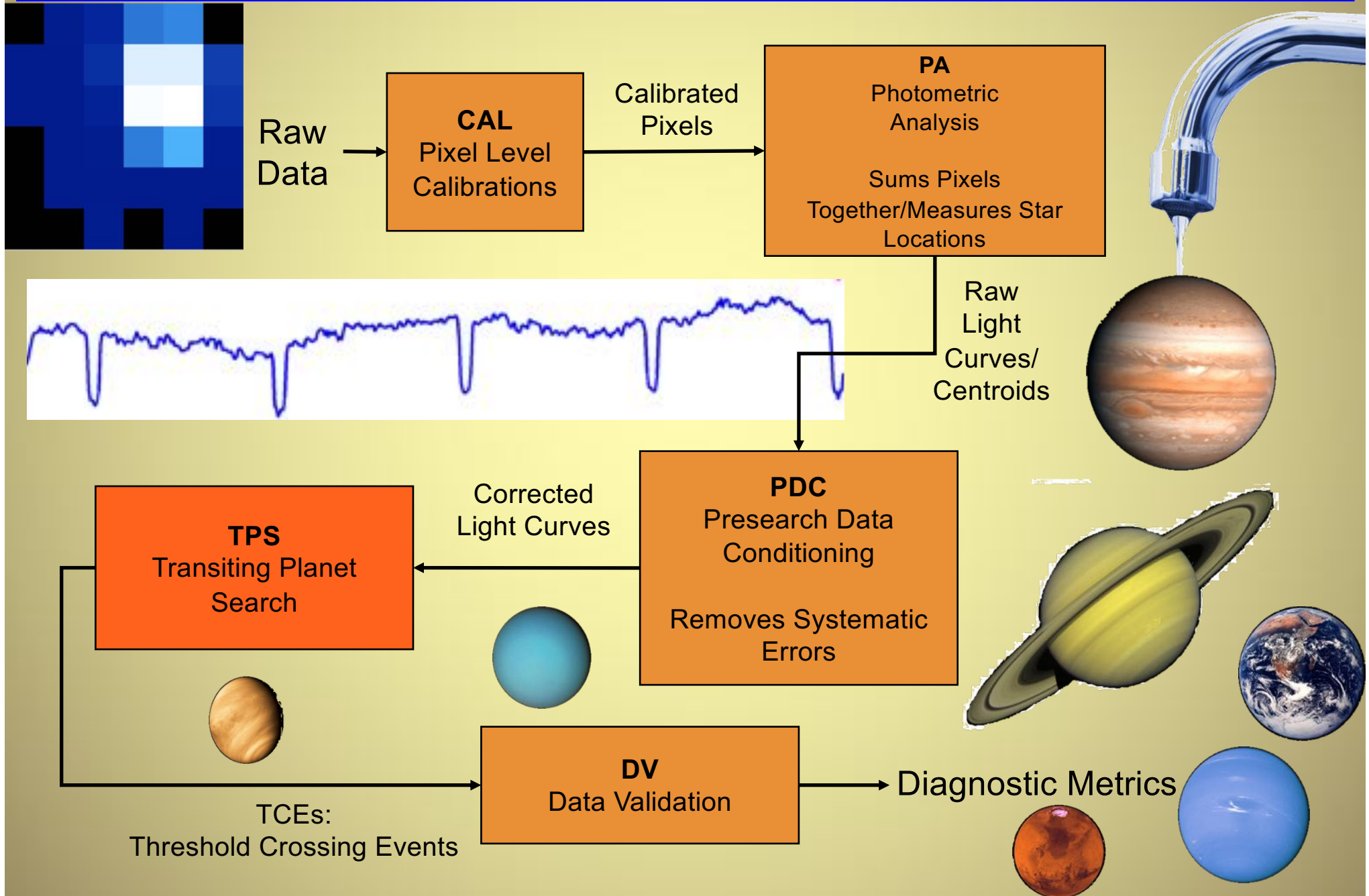


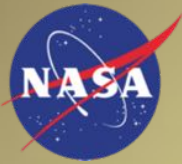
We apply a Maximum A Posteriori approach as per Stumpe et al. 2014



# The Kepler Science Pipeline: From Pixels To Planets

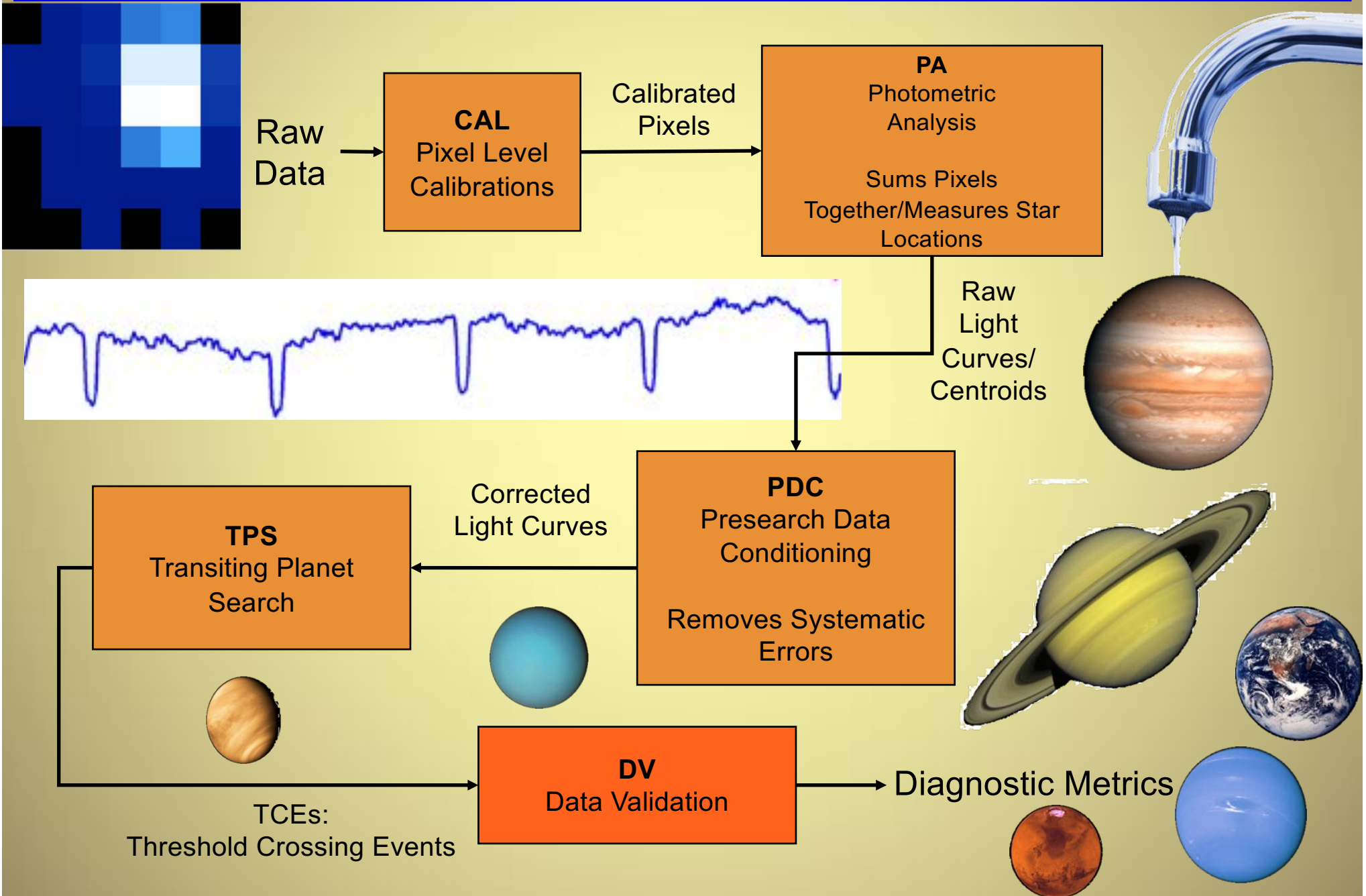
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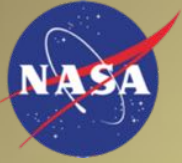




# The Kepler Science Pipeline: From Pixels To Planets

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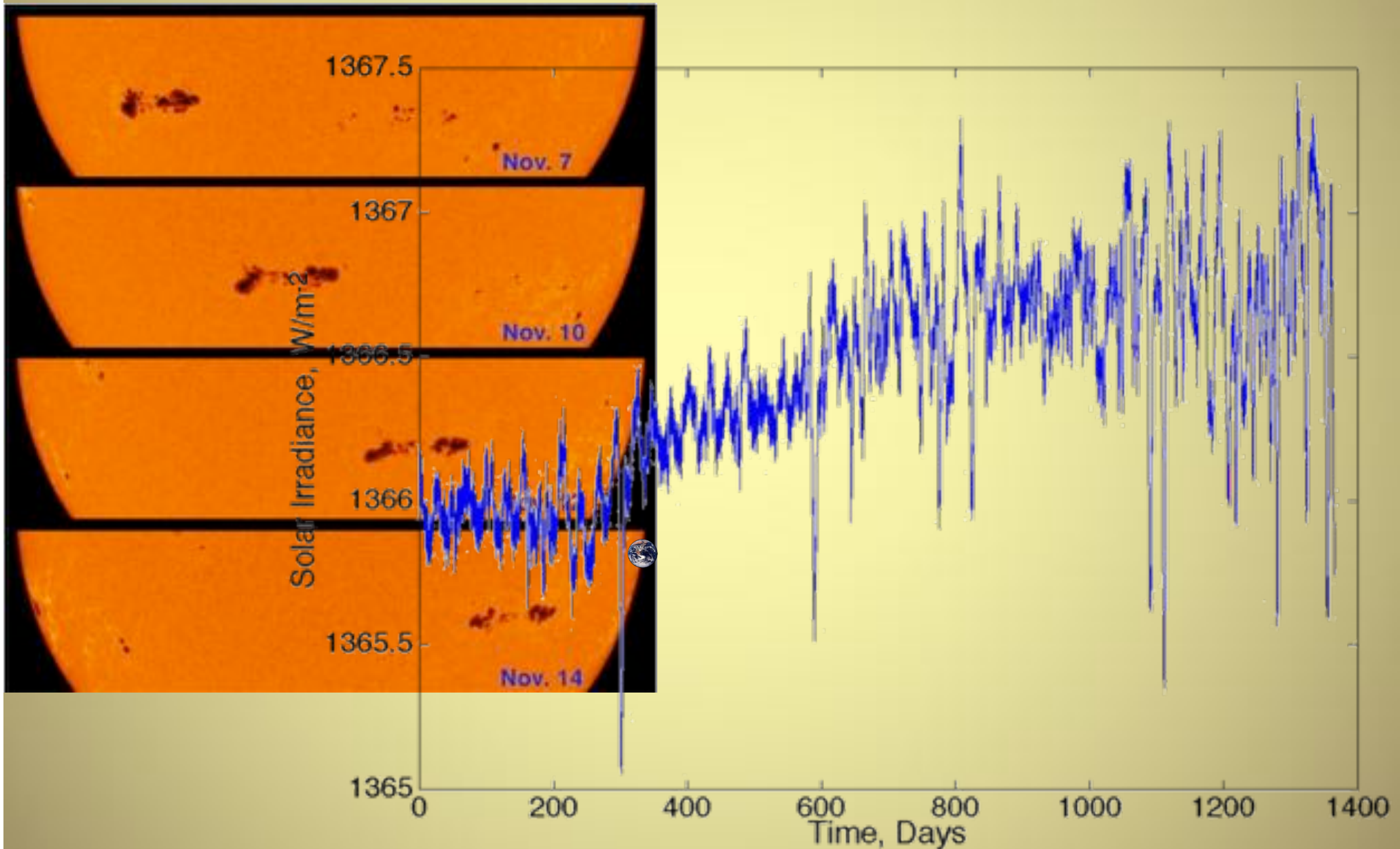




# Solar Variability

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# Detecting Deterministic Signals

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The problem:

- $H_0: x(n) = w(n)$  or
- $H_1: x(n) = s(n) + w(n)$

$s(n)$  is the signal of interest

$x(n)$  is the time series we observe

$w(n)$  is the observation noise (Gaussian)

The best method for detecting a known signal in additive Gaussian noise is a matched filter

A matched filter measures the correlation between the data and the signal, normalized by the rms variation of the observation noise



# Detection Statistics

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Define

$$T = \frac{x^T s}{\sigma_w \sqrt{s^T s}}$$

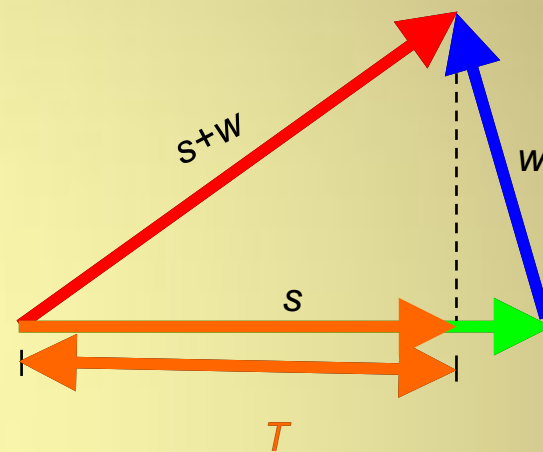
Under H0:

$$\langle T \rangle = 0, \quad \sigma_T^2 = 1$$

Under H1:

$$\langle T \rangle = \frac{1}{\sigma_w} \sqrt{s^T s}, \quad \sigma_T^2 = 1$$

If  $T < \gamma$ , then choose H0, if  $T > \gamma$ , then choose H1



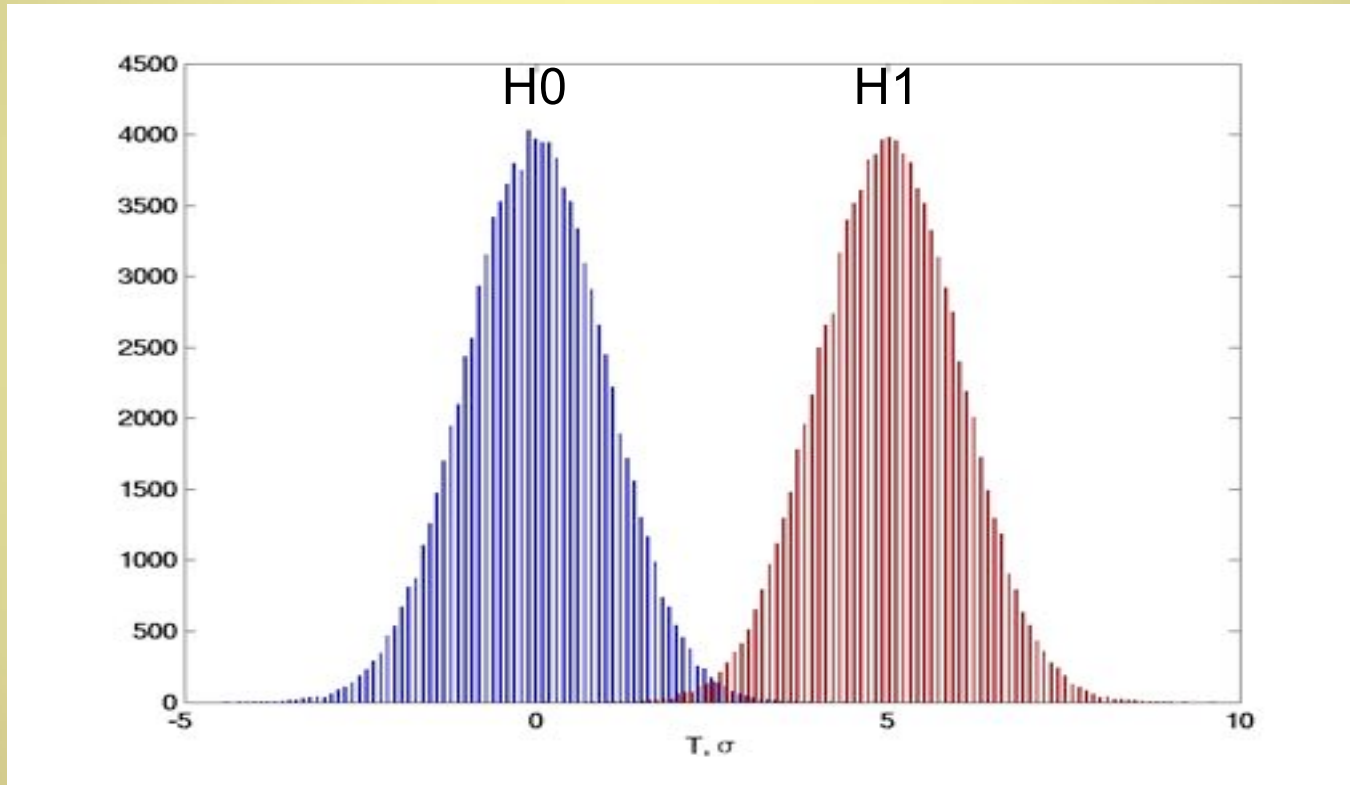


# Receiver Operating Curves

$T$  is a Gaussian random variable

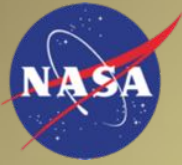
$$P_F = \frac{1}{\sqrt{2\pi}} \int_{\gamma}^{\infty} \exp\left(-\frac{1}{2} y^2\right) dy$$

$$P_D = \frac{1}{\sqrt{2\pi}} \int_{\gamma - \langle T \rangle}^{\infty} \exp\left(-\frac{1}{2} y^2\right) dy$$



How do we choose the threshold,  $\gamma$ ?

If amplitude of  $s$  not known, we generally set  $\gamma$  to control  $P_F$ .  
(Neyman-Pearson Criterion)



# Detection Statistics For Colored Noise *Kepler*

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$w$  is (colored) Gaussian noise with autocorrelation matrix  $R$   
 $x$  is the data  
 $s$  is the signal of interest

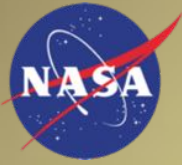
Decide  $s$  is present if  $T = \frac{x^T R^{-1} s}{\sqrt{s^T R^{-1} s}} = \frac{(Hx)^T (Hs)}{\sqrt{(Hs)^T (Hs)}} = \frac{\tilde{x}^T \tilde{s}}{\sqrt{\tilde{s}^T \tilde{s}}} > \gamma$

How do we determine  $R$ ?

Looks like a simple matched filter!

If the noise is stationary, we can work in the frequency domain:

$$T = \int \frac{X(f)S^*(f)}{P(f)} df / \sqrt{\int \frac{S(f)S^*(f)}{P(f)} df}$$



# PSDs for Solar-Like Variability

*Kepler*

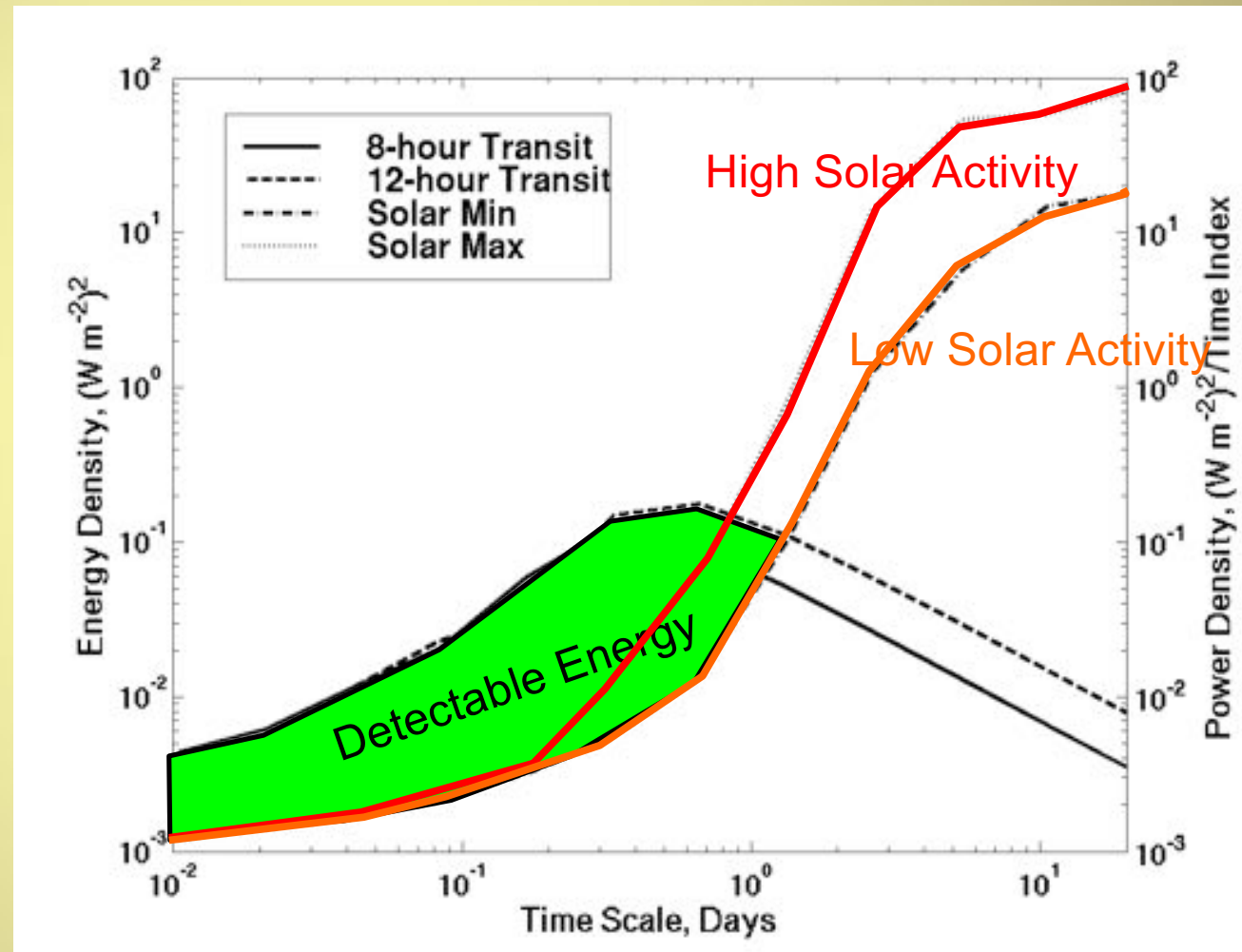
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Is stellar variability stationary?

No!

We must work in a joint time-frequency domain

Wavelets are a natural choice



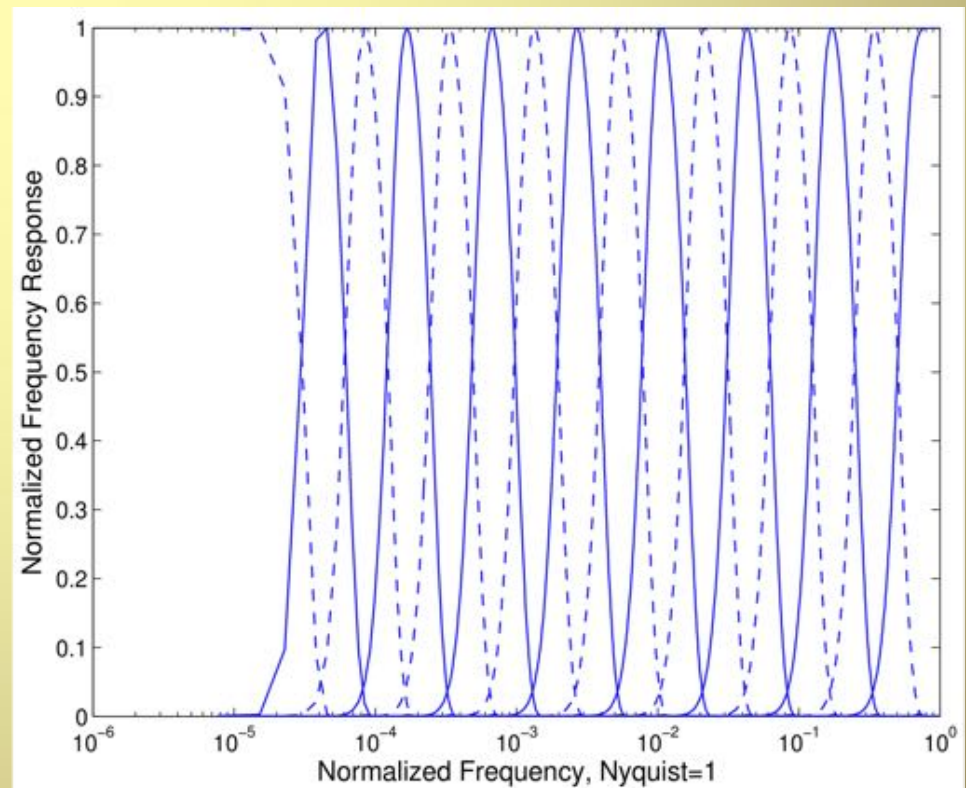
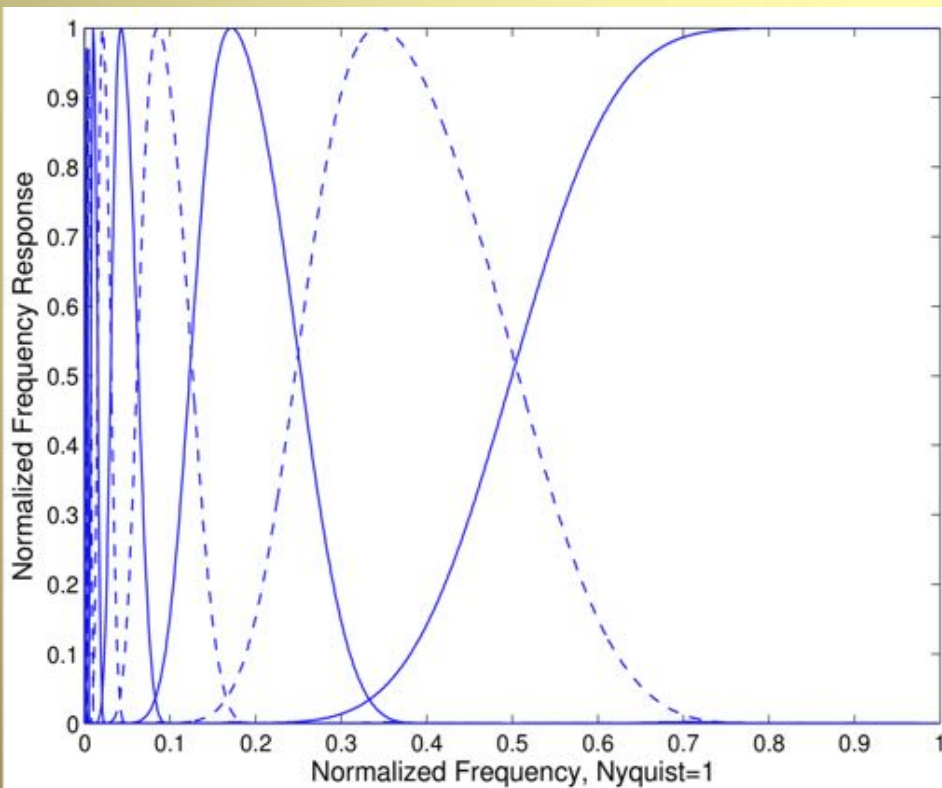


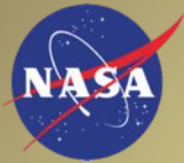
# A Wavelet-Based Approach

Filter-Bank Implementation of an Overcomplete Wavelet Transform

The time series  $x(n)$  is partitioned (filtered) into complementary channels

$$W_x(i,n) = \{h_1(n) * x(n), h_2(n) * x(n), \dots, h_M(n) * x(n)\} = \{x_1(n), x_2(n), \dots, x_m(n)\}$$

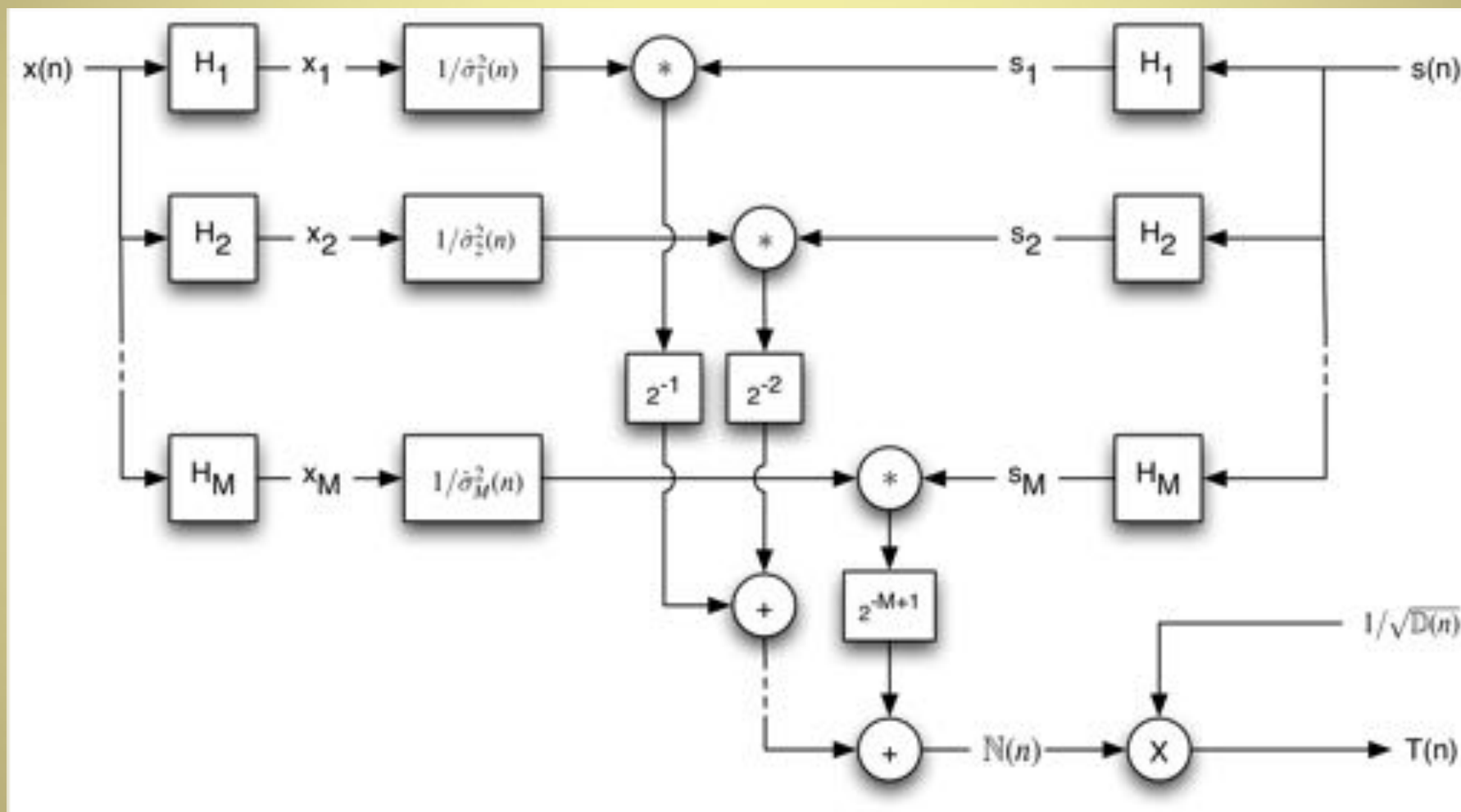


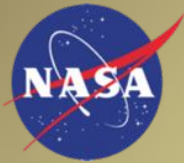


# Signal Flow Diagram

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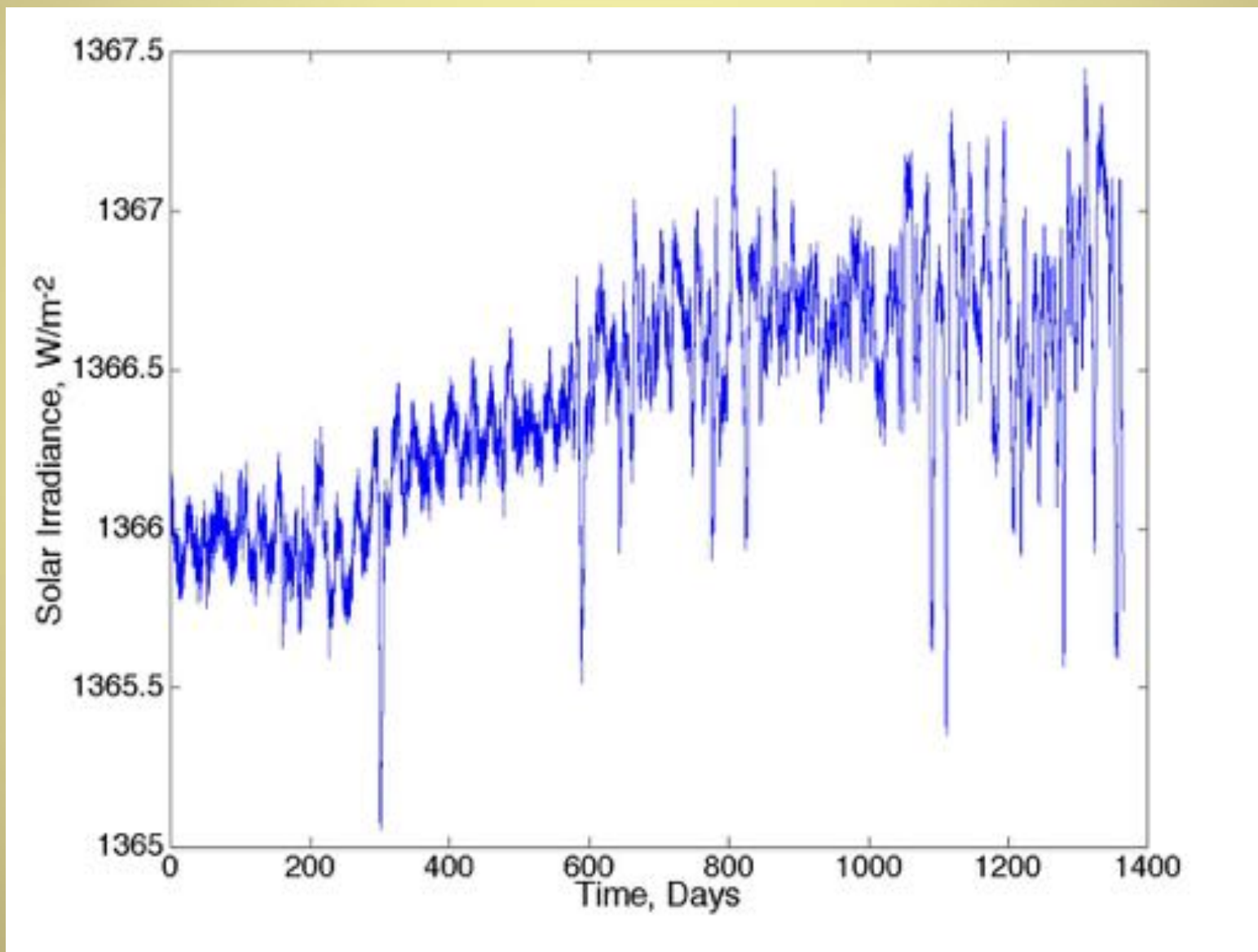




# Kepler-like Noise + Transits

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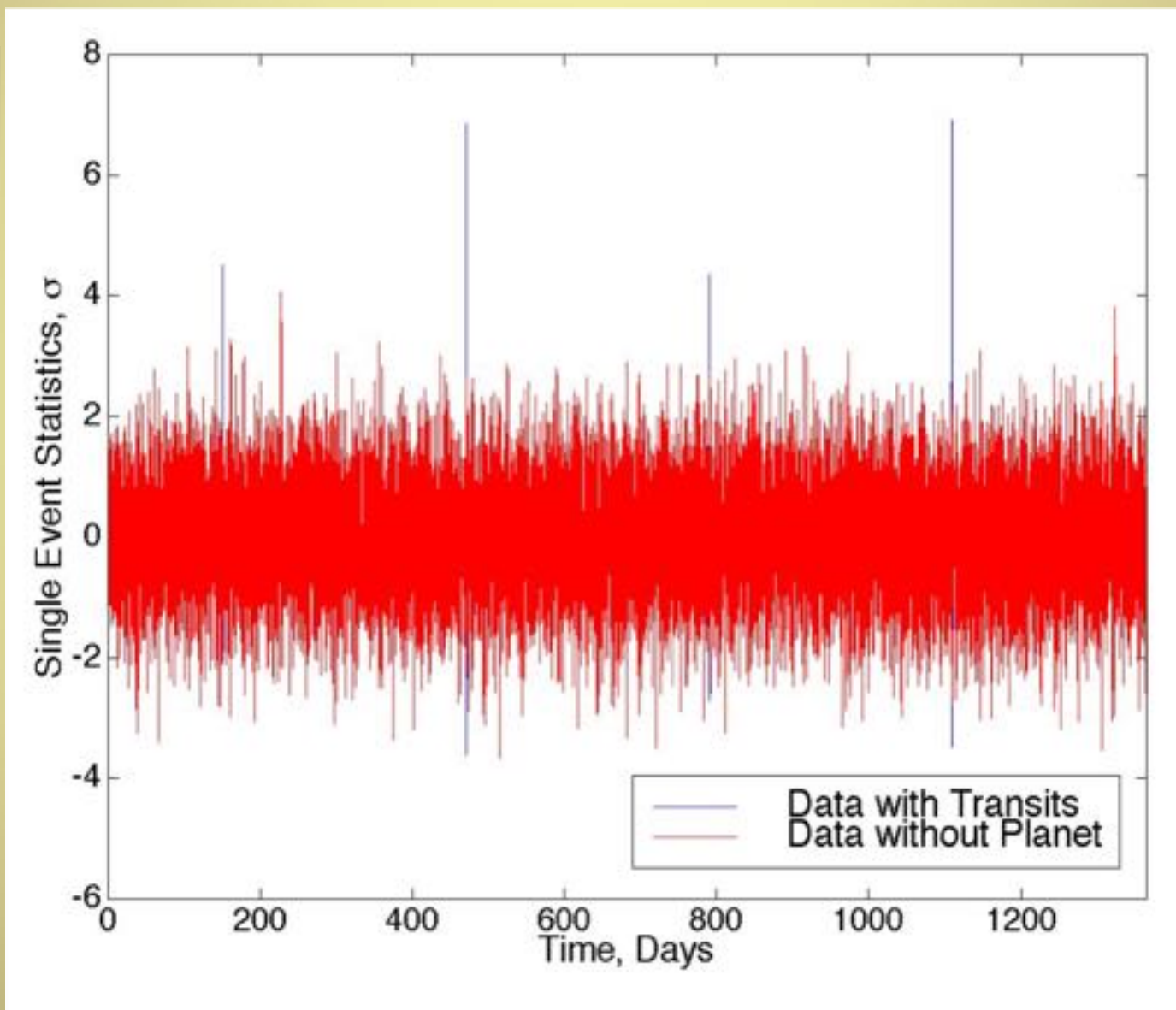




# Single Transit Statistics

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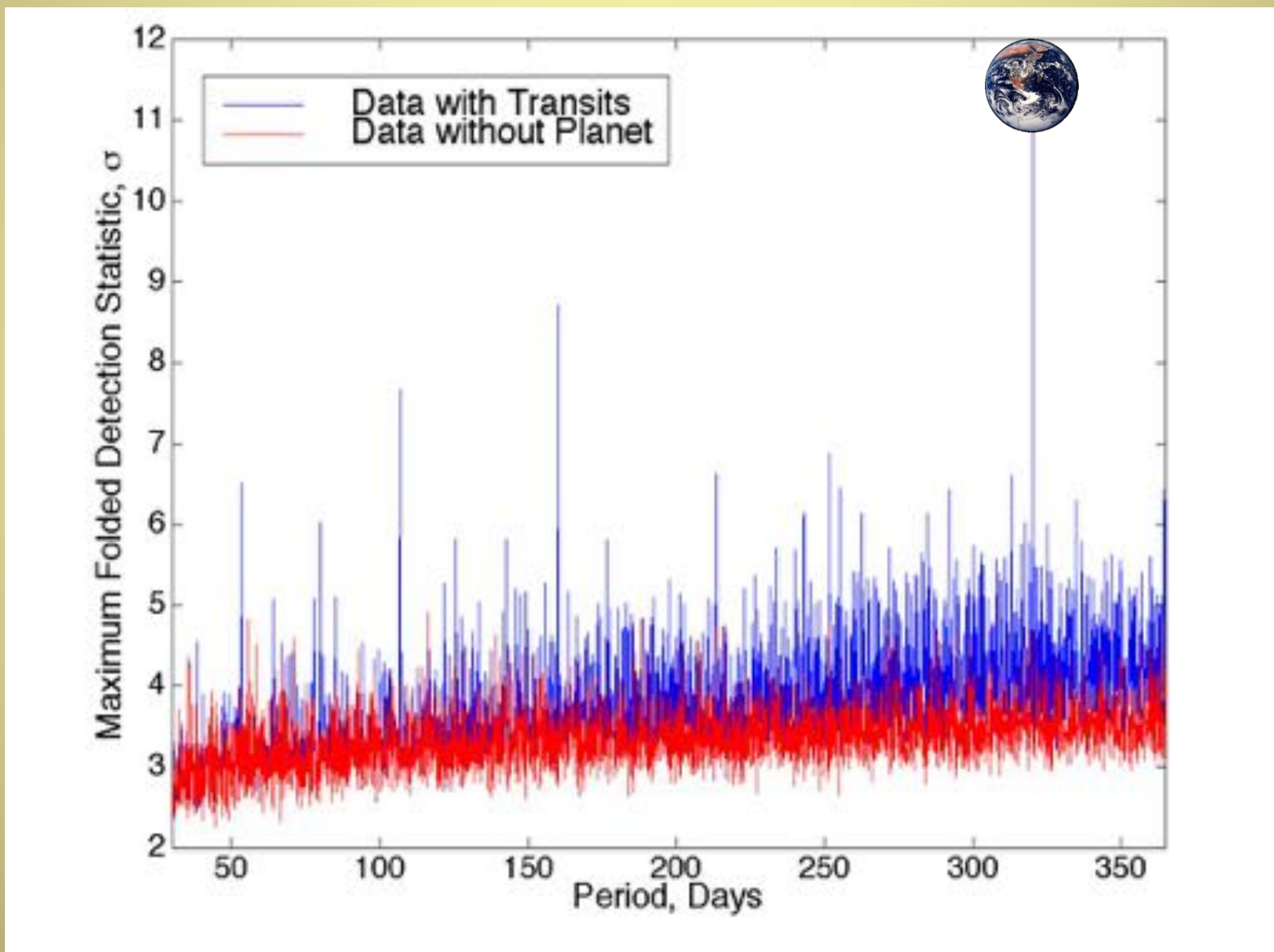


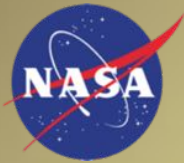


# Folded Transit Statistics

*Kepler*

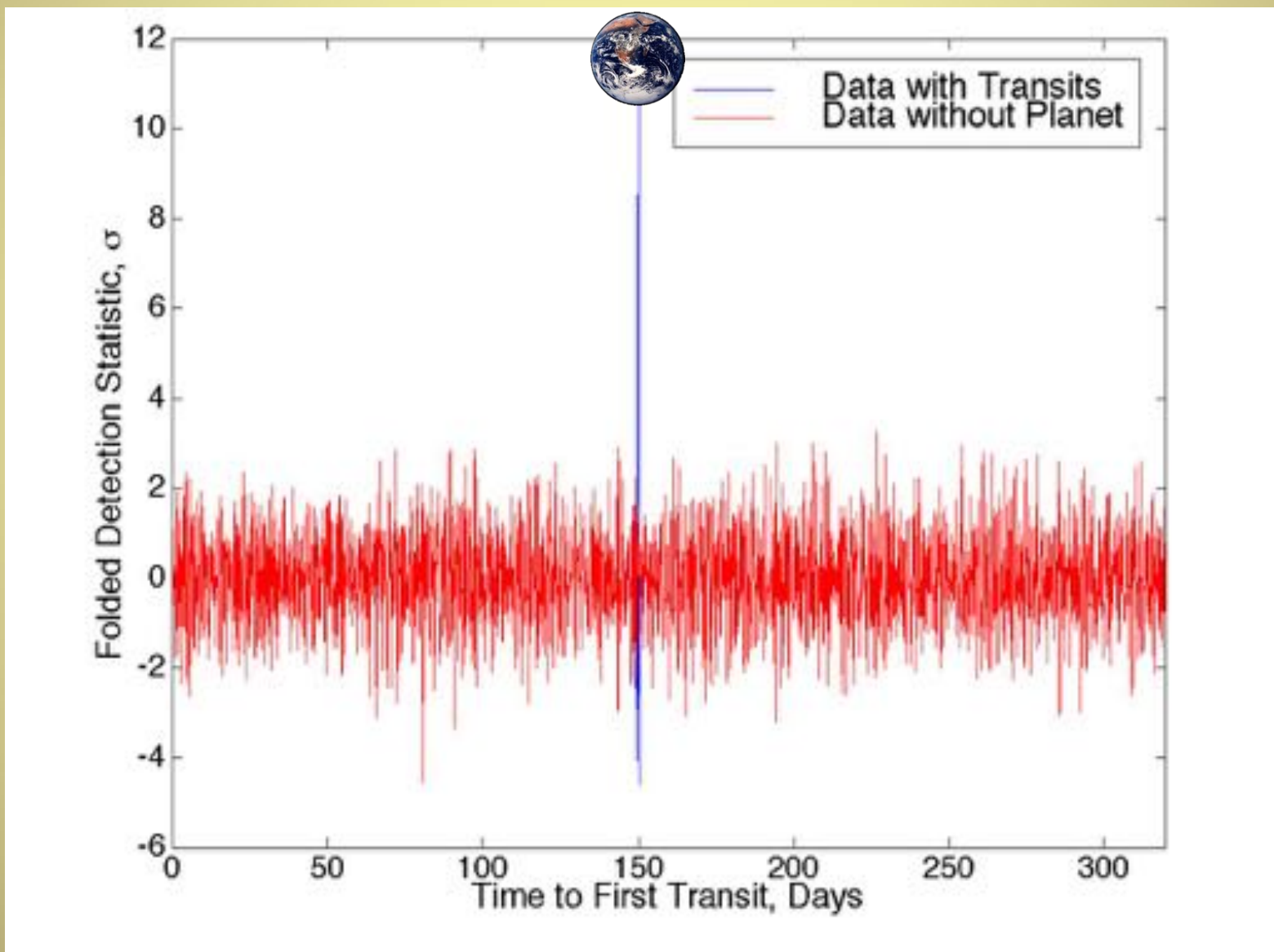
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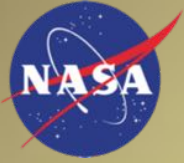




# Folded Statistics at Best-Matched Period *Kepler*

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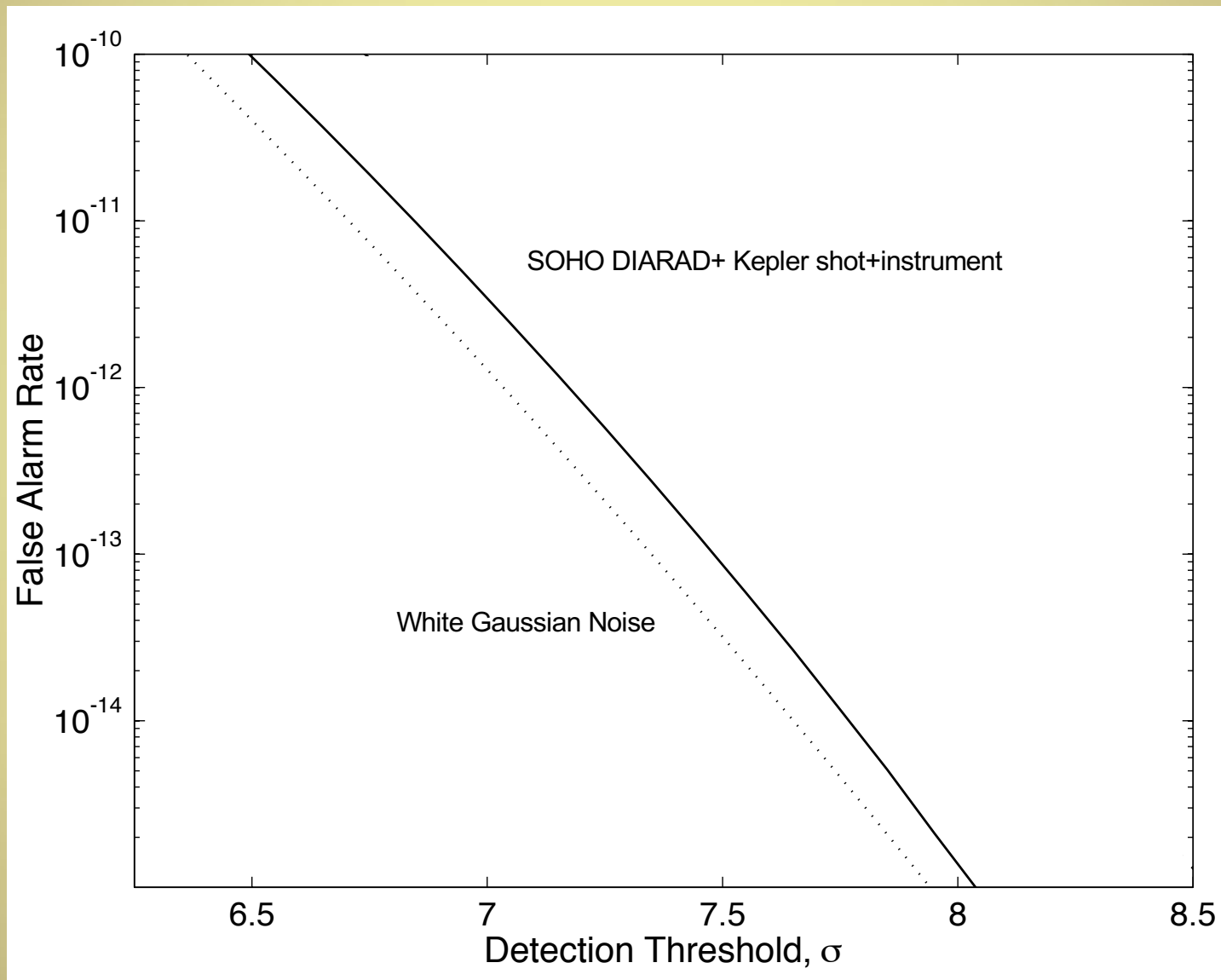


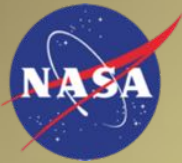


# Setting the Threshold

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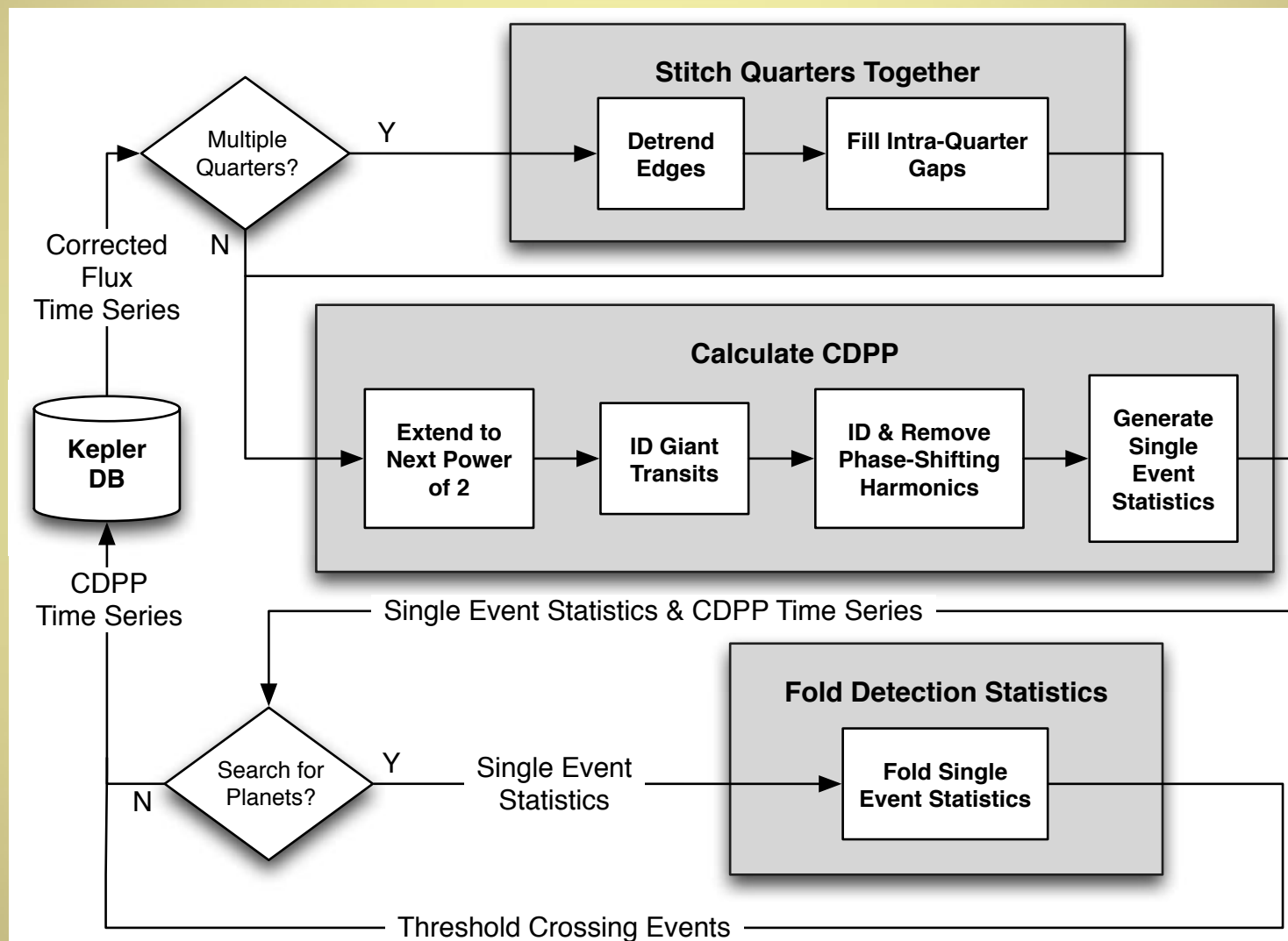




# Transiting Planet Search Architecture



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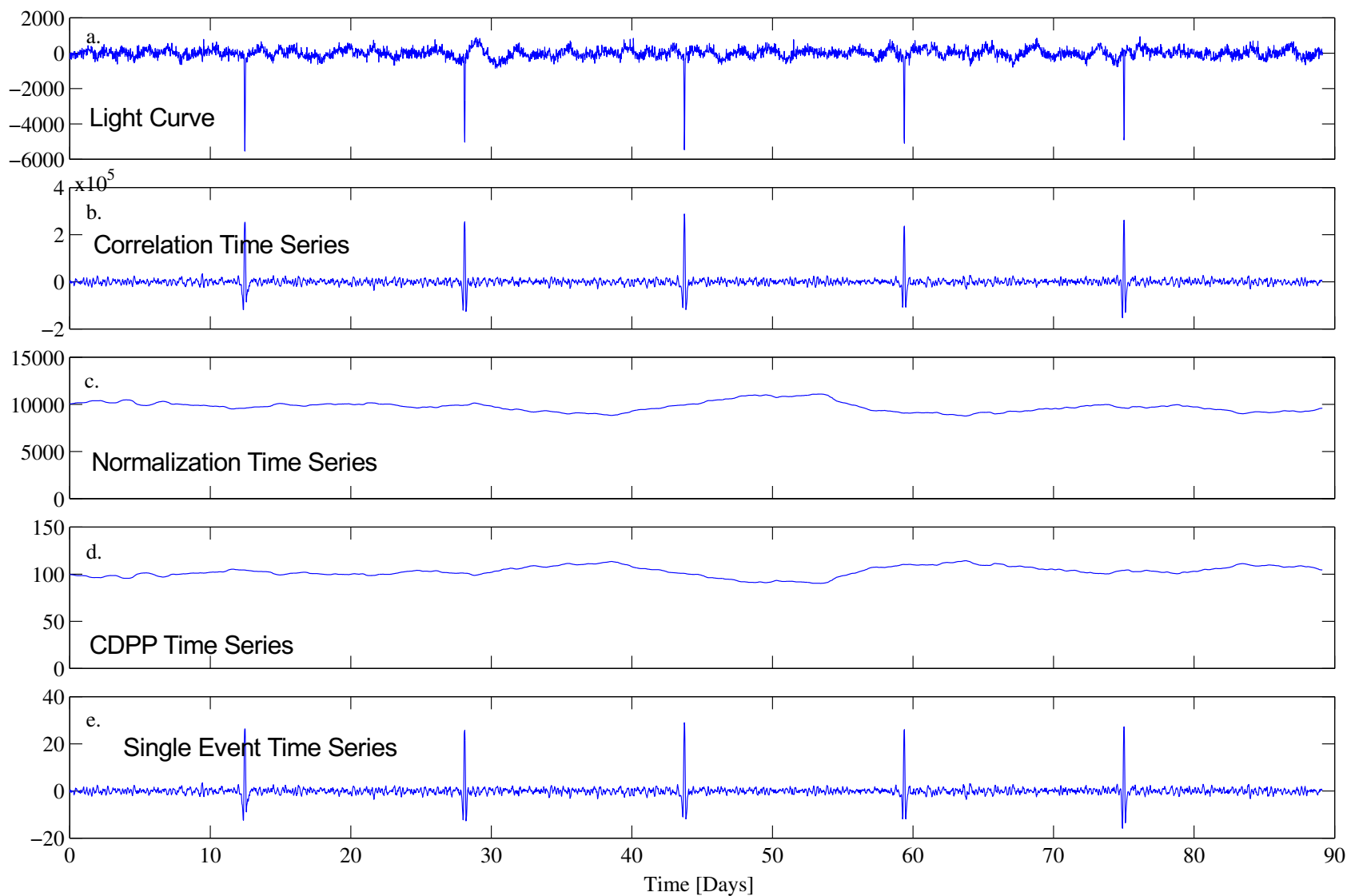


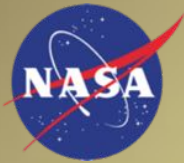


# A Kepler Example: Calculating CDDP

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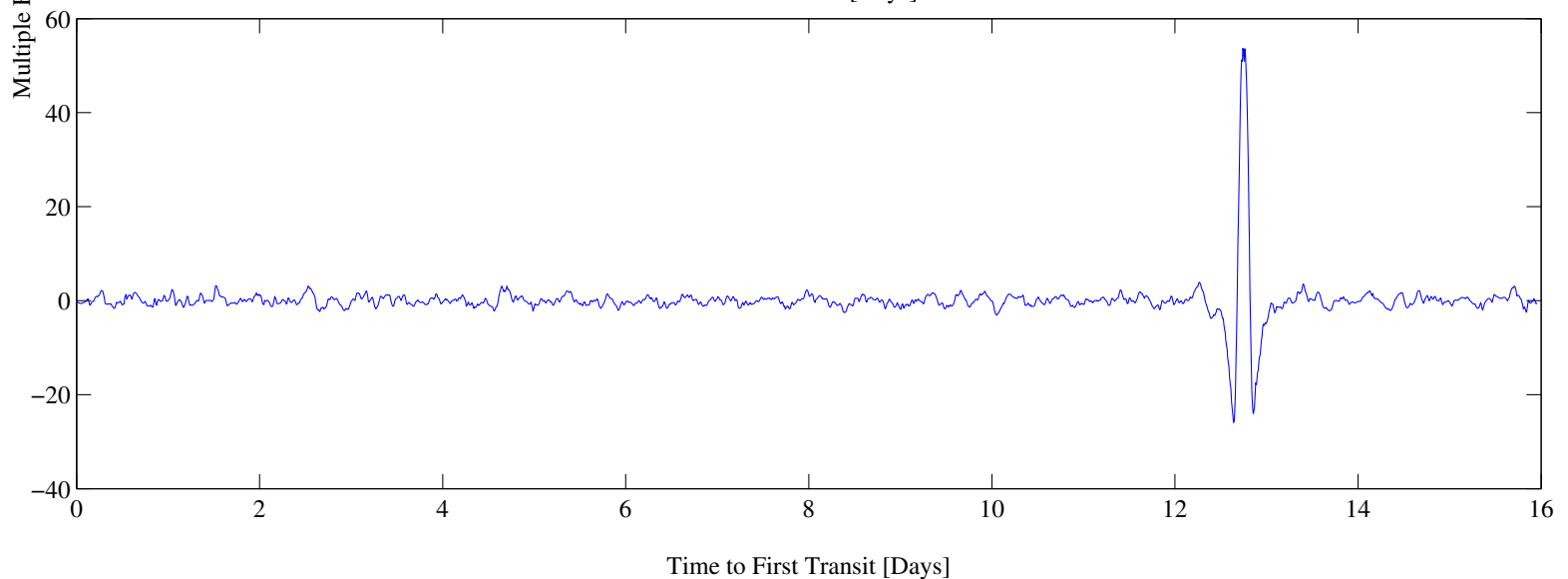
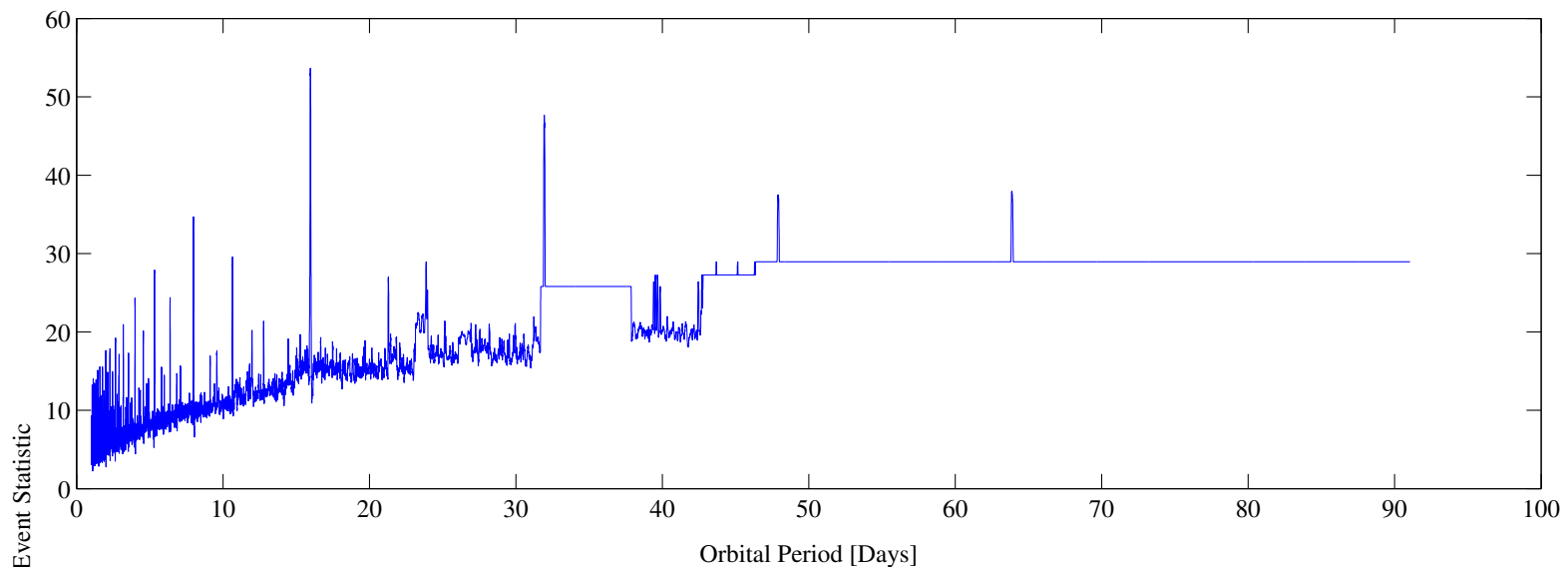




# A Kepler Example: Calculating CDDP



A Search for Earth-size Planets

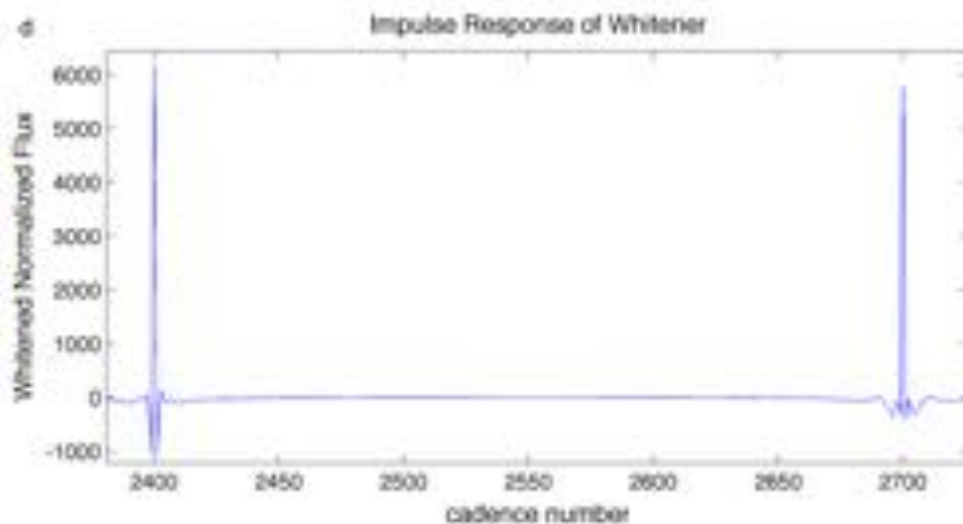
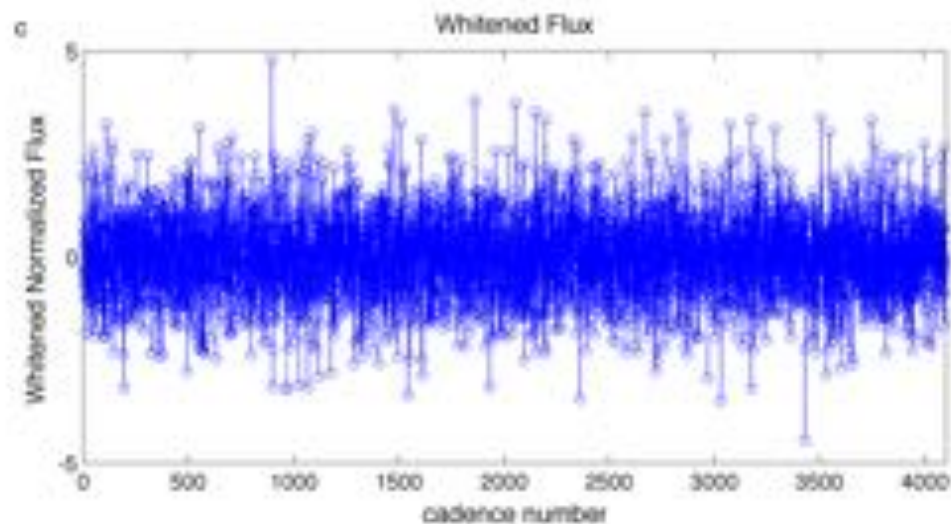
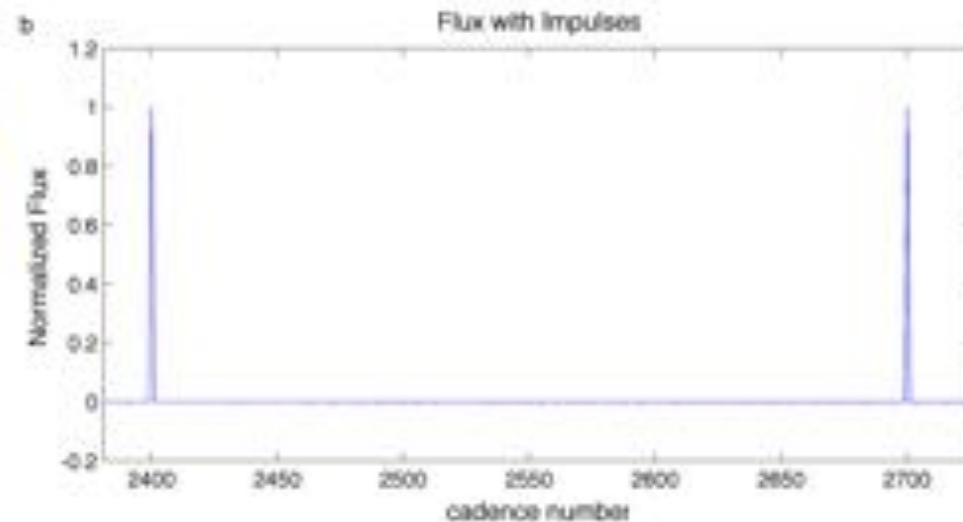
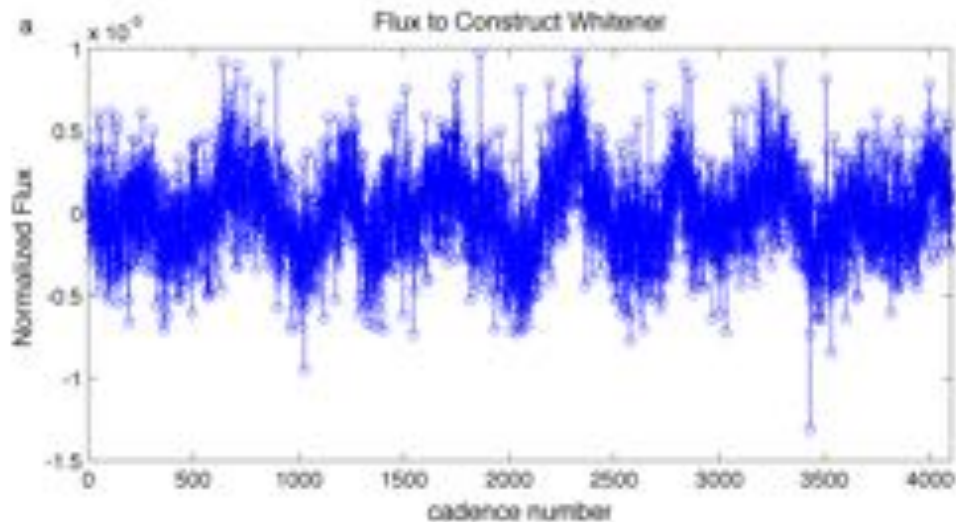




# A Kepler Example: Adaptive Whitening

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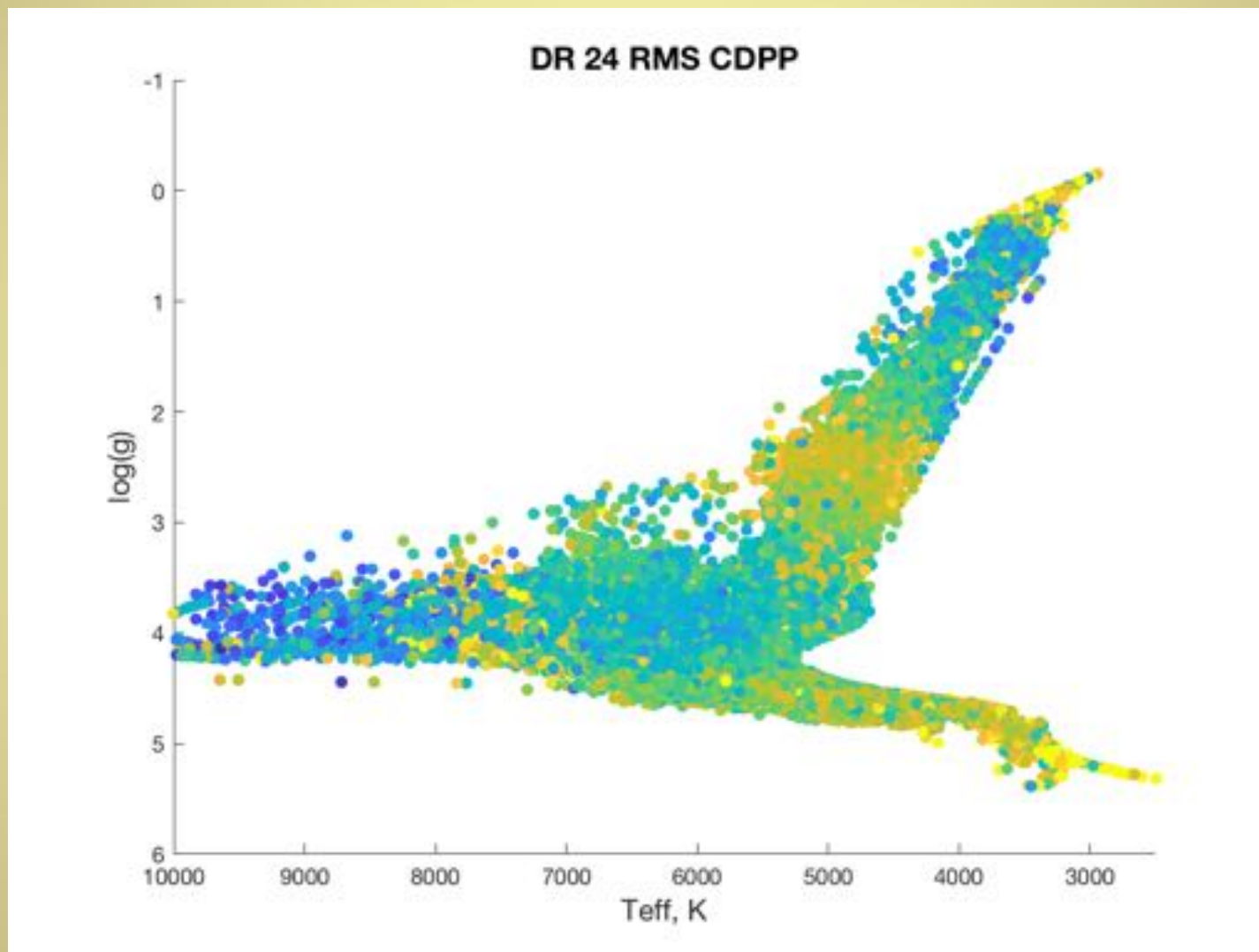




# Photometric Precision

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G dwarfs appear to be quiet, and M dwarfs appear to be much noisier



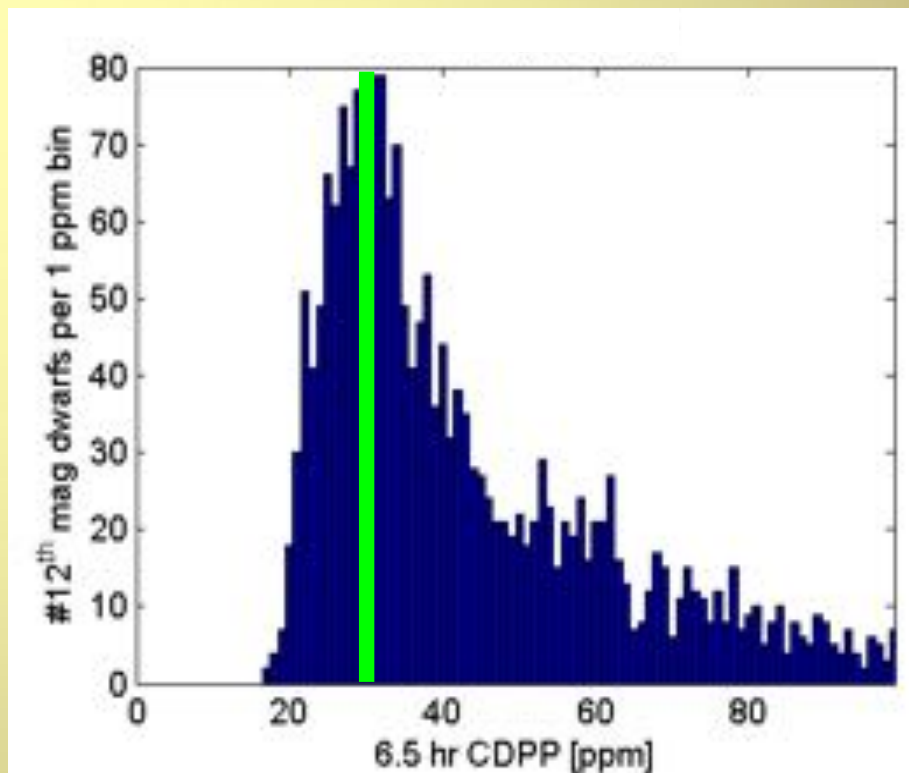
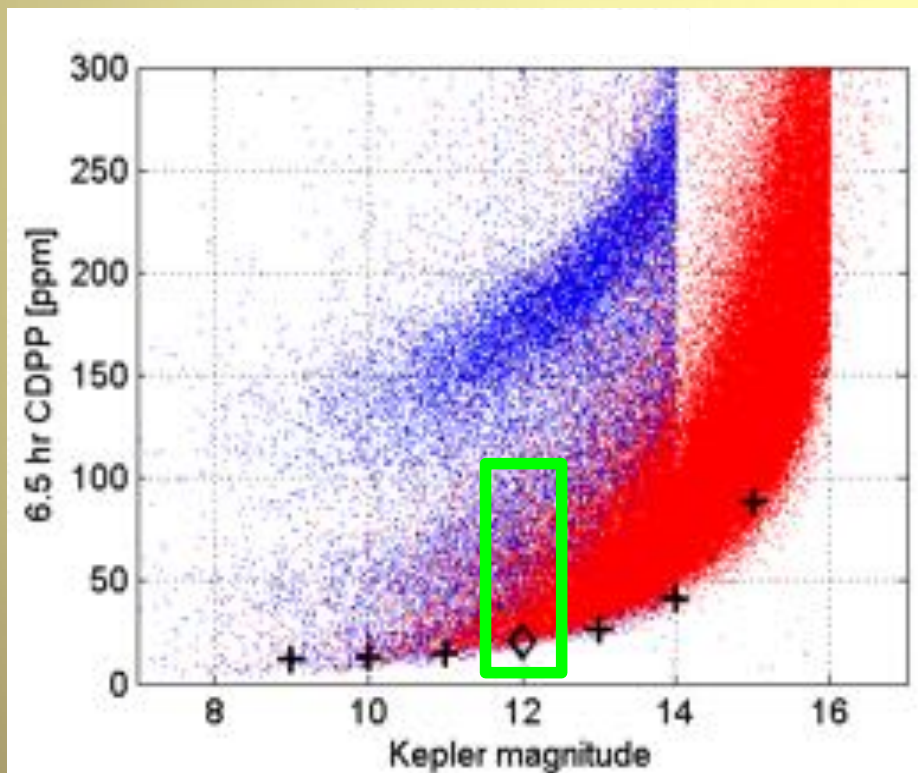
# Excess Stellar Variability

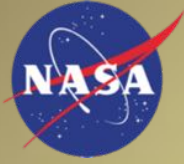


A Search for Earth-size Planets

Original Noise Budget  
( $K_p=12$ ):  
14 ppm Shot Noise  
10 ppm Instrument Noise  
10 ppm Stellar Variability  
=> 20 ppm Total Noise

Reality ( $11.5 \leq K_p \leq 12.5$ )  
17 ppm Shot Noise  
13 ppm Instrument Noise  
20 ppm Stellar Variability  
=> ~29 ppm Total Noise





# Summary

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- Stellar variability presents a fundamental limit on the detectability of transiting Earth-like planets
- Adaptive matched filters can provide near-optimal detection of Earth-size transits and characterize the observation noise
- Larger than expected stellar variability can be compensated for by increasing the duration of the campaign
- Controlling instrumental noise and systematics is also very important as shot noise, instrument noise and stellar variability should be comparable in a well designed mission