

Quality Report



Generated with Pix4Denterprise version 4.5.6



Important: Click on the different icons for:



Help to analyze the results in the Quality Report



Additional information about the sections



Click [here](#) for additional tips to analyze the Quality Report

Summary



| | |
|--|---|
| Project | 09-11-2023-PUG SLATINA_COMPLETARE_ORTO_2 |
| Processed | 2023-11-13 19:09:20 |
| Camera Model Name(s) | FC6310R_8.8_5472x3648 (RGB) |
| Average Ground Sampling Distance (GSD) | 2.92 cm / 1.15 in |
| Area Covered | 0.369 km ² / 36.8956 ha / 0.14 sq. mi. / 91.2182 acres |
| Time for Initial Processing (without report) | 04m:00s |

Quality Check



| | | |
|---------------------|---|--|
| Images | median of 4554 keypoints per image | |
| Dataset | 272 out of 338 images calibrated (80%), all images enabled | |
| Camera Optimization | 0.9% relative difference between initial and optimized internal camera parameters | |
| Matching | median of 1146.92 matches per calibrated image | |
| Georeferencing | yes, no 3D GCP | |

Preview

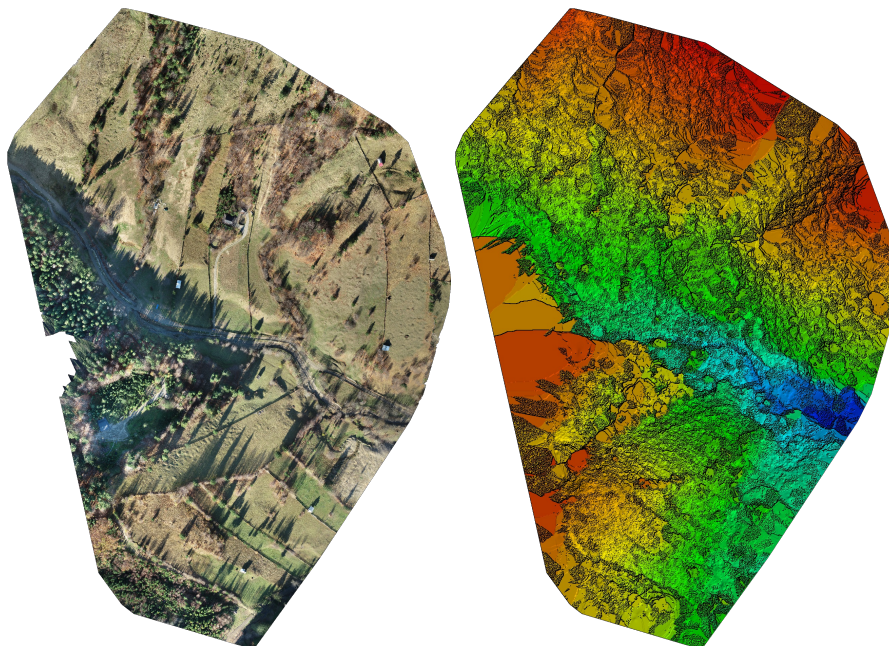


Figure 1: Orthomosaic and the corresponding sparse Digital Surface Model (DSM) before densification.

Calibration Details



| | |
|-----------------------------|----------------|
| Number of Calibrated Images | 272 out of 338 |
| Number of Geolocated Images | 338 out of 338 |

Initial Image Positions

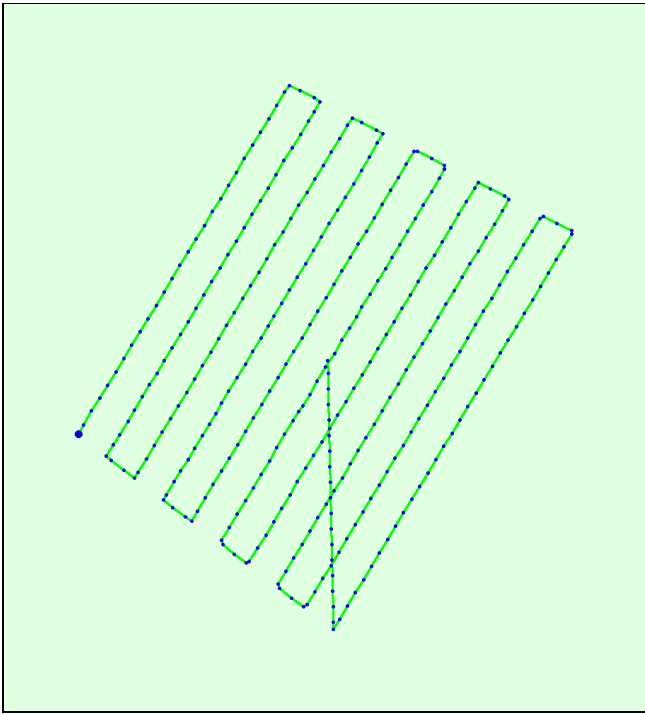


Figure 2: Top view of the initial image position. The green line follows the position of the images in time starting from the large blue dot.

Computed Image/GCPs/Manual Tie Points Positions



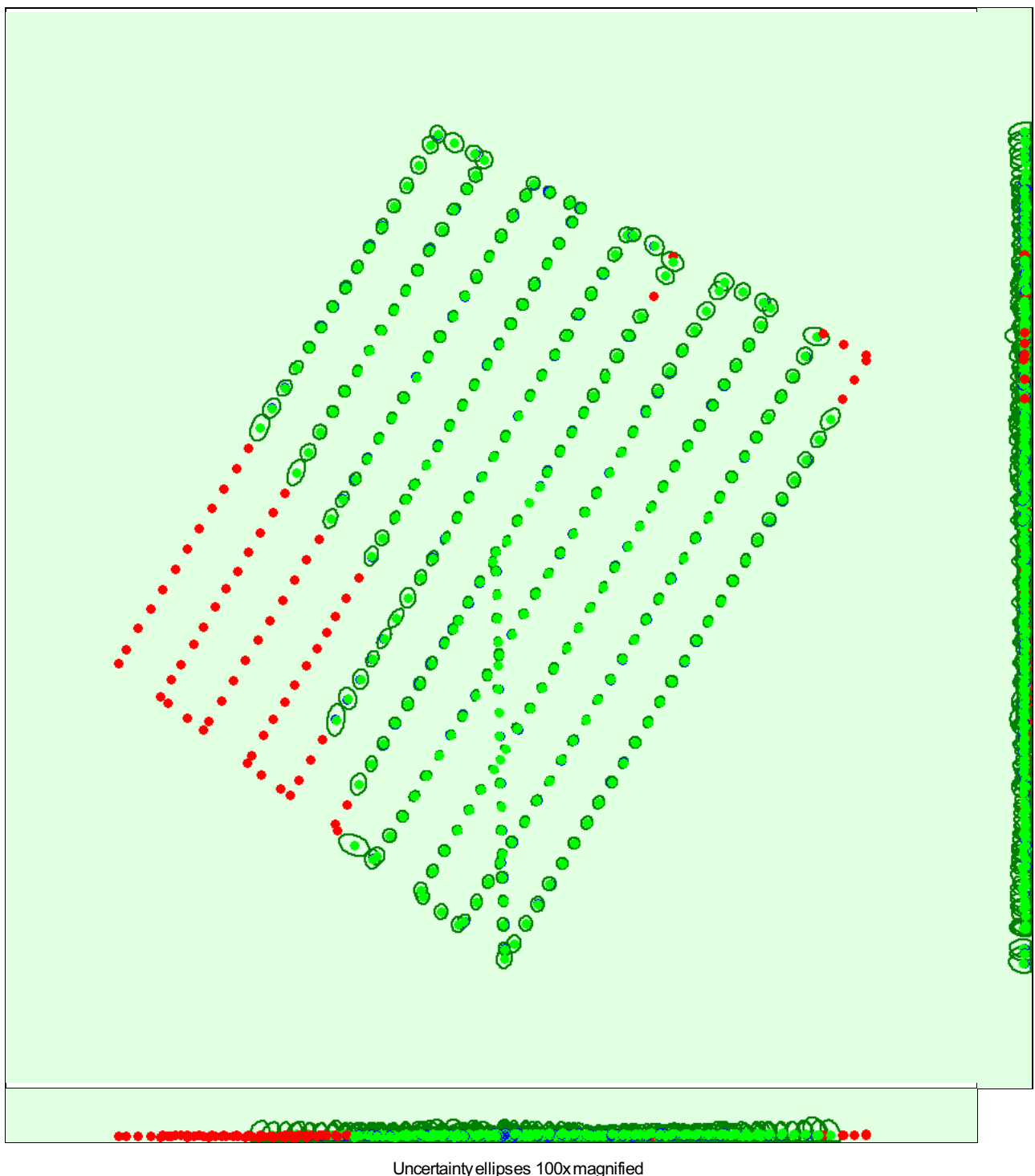


Figure 3: Offset between initial (blue dots) and computed (green dots) image positions as well as the offset between the GCPs initial positions (blue crosses) and their computed positions (green crosses) in the top-view (XY plane), front-view (XZ plane), and side-view (YZ plane). Red dots indicate disabled or uncalibrated images. Dark green ellipses indicate the absolute position uncertainty of the bundle block adjustment result.

? Absolute camera position and orientation uncertainties



| | X[m] | Y[m] | Z[m] | Omega [degree] | Phi [degree] | Kappa [degree] |
|-------|-------|-------|-------|----------------|--------------|----------------|
| Mean | 0.058 | 0.064 | 0.096 | 0.038 | 0.036 | 0.015 |
| Sigma | 0.016 | 0.018 | 0.022 | 0.013 | 0.013 | 0.008 |

? Overlap





Figure 4: Number of overlapping images computed for each pixel of the orthomosaic. Red and yellow areas indicate low overlap for which poor results may be generated. Green areas indicate an overlap of over 5 images for every pixel. Good quality results will be generated as long as the number of keypoint matches is also sufficient for these areas (see Figure 5 for keypoint matches).

Bundle Block Adjustment Details

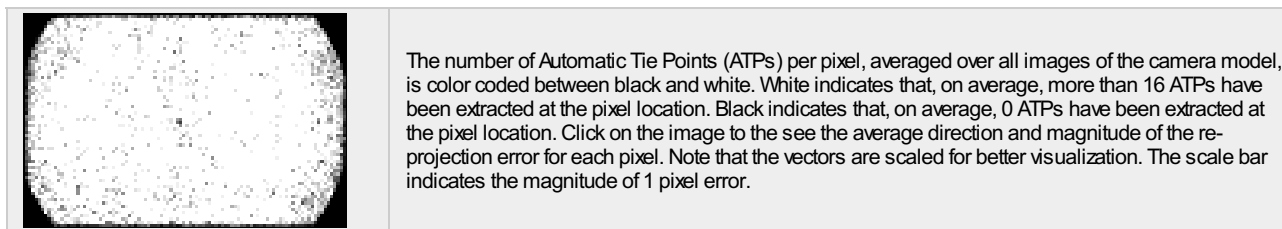
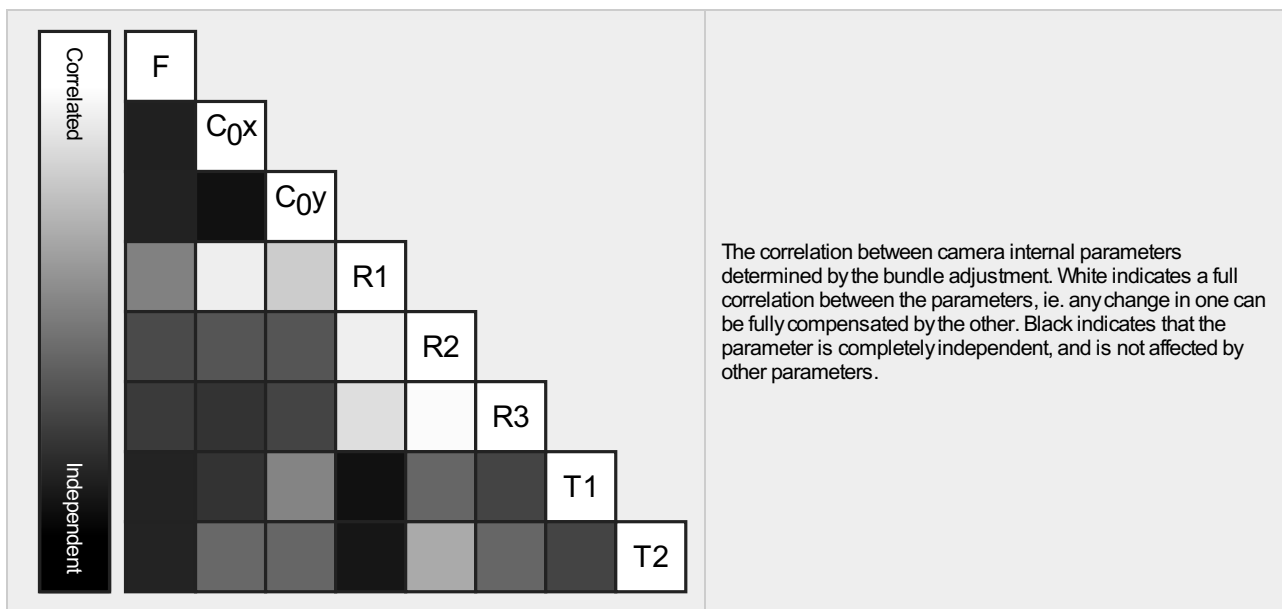
| | |
|--|--------|
| Number of 2D Keypoint Observations for Bundle Block Adjustment | 301202 |
| Number of 3D Points for Bundle Block Adjustment | 118820 |
| Mean Reprojection Error [pixels] | 0.098 |

Internal Camera Parameters

FC6310R_8.8_5472x3648 (RGB). Sensor Dimensions: 12.833 [mm] x 8.556 [mm]

EXIF ID: FC6310R_8.8_5472x3648

| | Focal Length | Principal Point x | Principal Point y | R1 | R2 | R3 | T1 | T2 |
|-----------------------|--------------------------------|--------------------------------|--------------------------------|--------|-------|--------|-------|--------|
| Initial Values | 3658.300 [pixel] 8.580 [mm] | 2722.500 [pixel] 6.385 [mm] | 1835.100 [pixel] 4.304 [mm] | -0.269 | 0.112 | -0.033 | 0.000 | -0.001 |
| Optimized Values | 3691.266 [pixel] 8.657 [mm] | 2702.064 [pixel] 6.337 [mm] | 1810.068 [pixel] 4.245 [mm] | -0.288 | 0.133 | -0.040 | 0.000 | -0.000 |
| Uncertainties (Sigma) | 0.944 [pixel] 0.002 [mm] | 0.418 [pixel] 0.001 [mm] | 0.363 [pixel] 0.001 [mm] | 0.000 | 0.001 | 0.000 | 0.000 | 0.000 |



2D Keypoints Table

| | Number of 2D Keypoints per Image | Number of Matched 2D Keypoints per Image |
|--------|----------------------------------|--|
| Median | 4554 | 1147 |
| Min | 3163 | 95 |
| Max | 6374 | 2320 |
| Mean | 4619 | 1107 |

3D Points from 2D Keypoint Matches

| | Number of 3D Points Observed |
|--------------|------------------------------|
| In 2 Images | 87872 |
| In 3 Images | 17265 |
| In 4 Images | 6447 |
| In 5 Images | 3147 |
| In 6 Images | 1542 |
| In 7 Images | 843 |
| In 8 Images | 558 |
| In 9 Images | 383 |
| In 10 Images | 257 |
| In 11 Images | 170 |
| In 12 Images | 110 |
| In 13 Images | 68 |
| In 14 Images | 60 |
| In 15 Images | 38 |
| In 16 Images | 28 |
| In 17 Images | 16 |
| In 18 Images | 7 |
| In 19 Images | 5 |
| In 20 Images | 3 |
| In 21 Images | 1 |

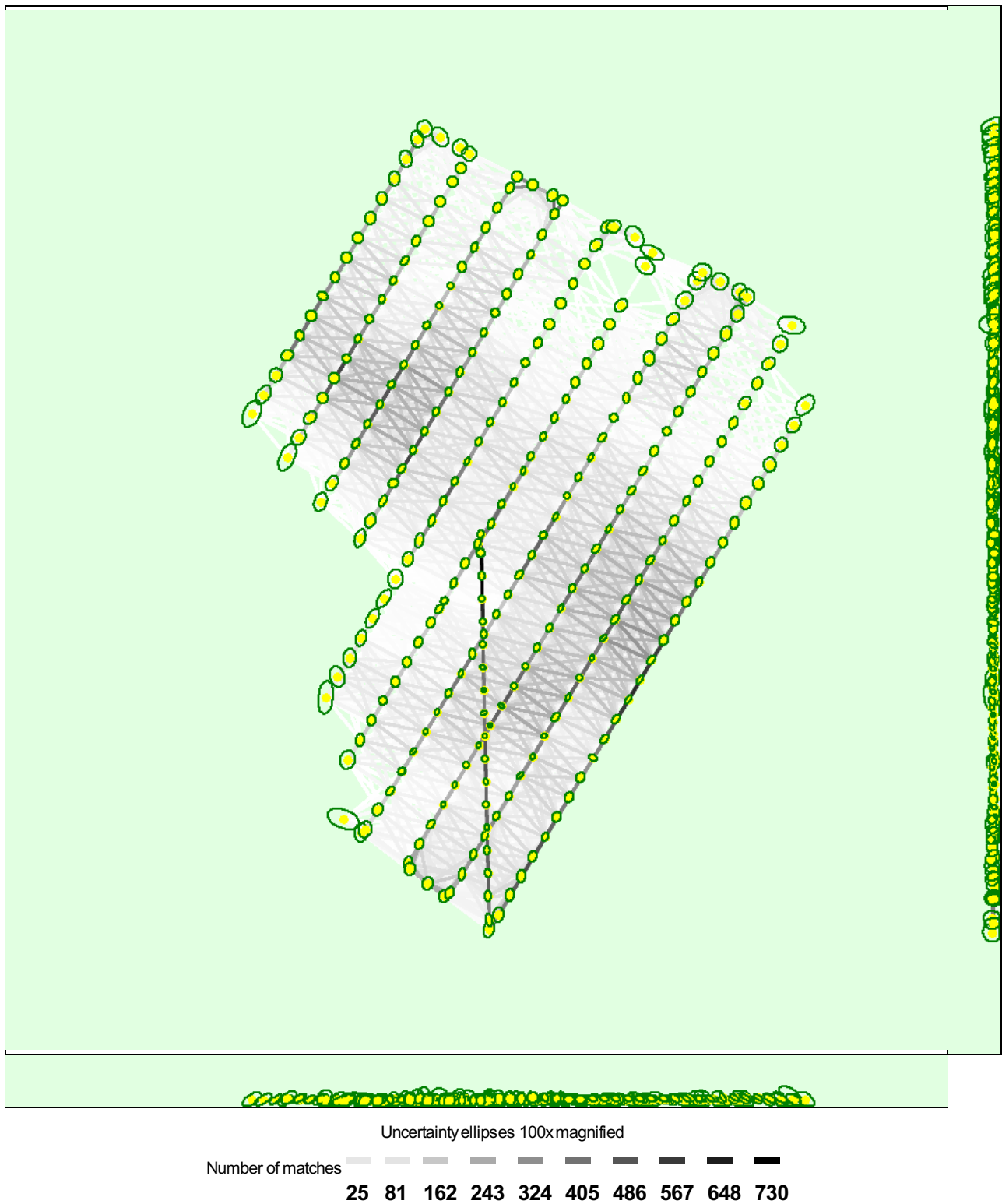


Figure 5: Computed image positions with links between matched images. The darkness of the links indicates the number of matched 2D keypoints between the images. Bright links indicate weak links and require manual tie points or more images. Dark green ellipses indicate the relative camera position uncertainty of the bundle block adjustment result.

Relative camera position and orientation uncertainties

| | X[m] | Y[m] | Z[m] | Omega [degree] | Phi [degree] | Kappa [degree] |
|-------|-------|-------|-------|----------------|--------------|----------------|
| Mean | 0.050 | 0.058 | 0.051 | 0.036 | 0.033 | 0.014 |
| Sigma | 0.019 | 0.021 | 0.021 | 0.017 | 0.016 | 0.008 |

Geolocation Details



Absolute Geolocation Variance



| Min Error [m] | Max Error [m] | Geolocation Error X [%] | Geolocation Error Y [%] | Geolocation Error Z [%] |
|---------------|---------------|-------------------------|-------------------------|-------------------------|
| - | -4.41 | 0.00 | 0.00 | 0.00 |
| -4.41 | -3.53 | 0.00 | 0.00 | 0.00 |
| -3.53 | -2.65 | 0.00 | 0.00 | 0.00 |
| -2.65 | -1.76 | 0.00 | 0.00 | 0.00 |
| -1.76 | -0.88 | 1.10 | 0.37 | 5.51 |
| -0.88 | 0.00 | 45.96 | 47.79 | 43.38 |
| 0.00 | 0.88 | 52.94 | 51.47 | 48.53 |
| 0.88 | 1.76 | 0.00 | 0.37 | 2.57 |
| 1.76 | 2.65 | 0.00 | 0.00 | 0.00 |
| 2.65 | 3.53 | 0.00 | 0.00 | 0.00 |
| 3.53 | 4.41 | 0.00 | 0.00 | 0.00 |
| 4.41 | - | 0.00 | 0.00 | 0.00 |
| Mean [m] | | -0.004611 | 0.006439 | -0.009593 |
| Sigma [m] | | 0.298066 | 0.279723 | 0.500957 |
| RMS Error [m] | | 0.298102 | 0.279797 | 0.501049 |

Min Error and Max Error represent geolocation error intervals between -1.5 and 1.5 times the maximum accuracy of all the images. Columns X, Y, Z show the percentage of images with geolocation errors within the predefined error intervals. The geolocation error is the difference between the initial and computed image positions. Note that the image geolocation errors do not correspond to the accuracy of the observed 3D points.

Relative Geolocation Variance



| Relative Geolocation Error | Images X [%] | Images Y [%] | Images Z [%] |
|-----------------------------------|--------------|--------------|--------------|
| [-1.00, 1.00] | 99.63 | 100.00 | 100.00 |
| [-2.00, 2.00] | 100.00 | 100.00 | 100.00 |
| [-3.00, 3.00] | 100.00 | 100.00 | 100.00 |
| Mean of Geolocation Accuracy [m] | 1.212870 | 1.212870 | 2.636317 |
| Sigma of Geolocation Accuracy [m] | 0.050023 | 0.050023 | 0.104502 |

Images X, Y, Z represent the percentage of images with a relative geolocation error in X, Y, Z.

| Geolocation Orientational Variance | RMS [degree] |
|------------------------------------|--------------|
| Omega | 0.610 |
| Phi | 1.341 |
| Kappa | 5.669 |

Geolocation RMS error of the orientation angles given by the difference between the initial and computed image orientation angles.

Initial Processing Details



System Information



| | |
|------------------|---|
| Hardware | CPU: Intel(R) Core(TM) i9-9900 CPU @ 3.10GHz RAM: 80GB GPU: NVIDIA GeForce RTX 3060 Ti (Driver: 31.0.15.3758) |
| Operating System | Windows 10 Pro, 64-bit |

Coordinate Systems



| | |
|--------------------------|----------------------|
| Image Coordinate System | WGS 84 |
| Output Coordinate System | WGS 84 / UTMzone 35N |

Processing Options



| | |
|--------------------------------|--|
| Detected Template | No Template Available |
| Keypoints Image Scale | Custom, Image Scale: 0.25 |
| Advanced: Matching Image Pairs | Aerial Grid or Corridor |
| Advanced: Matching Strategy | Use Geometrically Verified Matching: no |
| Advanced: Keypoint Extraction | Targeted Number of Keypoints: Automatic |
| Advanced: Calibration | Calibration Method: Standard Internal Parameters Optimization: All External Parameters Optimization: All Rematch: Auto, yes |

Point Cloud Densification details



Processing Options



| | |
|--------------------------------------|--|
| Image Scale | multiscale, 1/4 (Quarter image size, Fast) |
| Point Density | Optimal |
| Minimum Number of Matches | 3 |
| 3D Textured Mesh Generation | yes |
| 3D Textured Mesh Settings: | Resolution: Medium Resolution (default) Color Balancing: no |
| LOD | Generated: no |
| Advanced: 3D Textured Mesh Settings | Sample Density Divider: 1 |
| Advanced: Image Groups | group1 |
| Advanced: Use Processing Area | yes |
| Advanced: Use Annotations | yes |
| Time for Point Cloud Densification | 07m:09s |
| Time for Point Cloud Classification | NA |
| Time for 3D Textured Mesh Generation | 07m:02s |

Results



| | |
|---------------------------------------|---------|
| Number of Generated Tiles | 1 |
| Number of 3D Densified Points | 8587722 |
| Average Density (per m ³) | 36.68 |

DSM, Orthomosaic and Index Details



Processing Options



| | |
|---------------------------------|---|
| DSM and Orthomosaic Resolution | 5 [cm/pixel] |
| DSM Filters | Noise Filtering: yes Surface Smoothing: yes, Type: Sharp |
| Raster DSM | Generated: yes Method: Inverse Distance Weighting Merge Tiles: yes |
| Orthomosaic | Generated: yes Merge Tiles: yes GeoTIFF Without Transparency: no Google Maps Tiles and KML: no |
| Time for DSM Generation | 04m:23s |
| Time for Orthomosaic Generation | 24m:02s |
| Time for DTM Generation | 00s |

| | |
|-------------------------------------|-----|
| Time for Contour Lines Generation | 00s |
| Time for Reflectance Map Generation | 00s |
| Time for Index Map Generation | 00s |