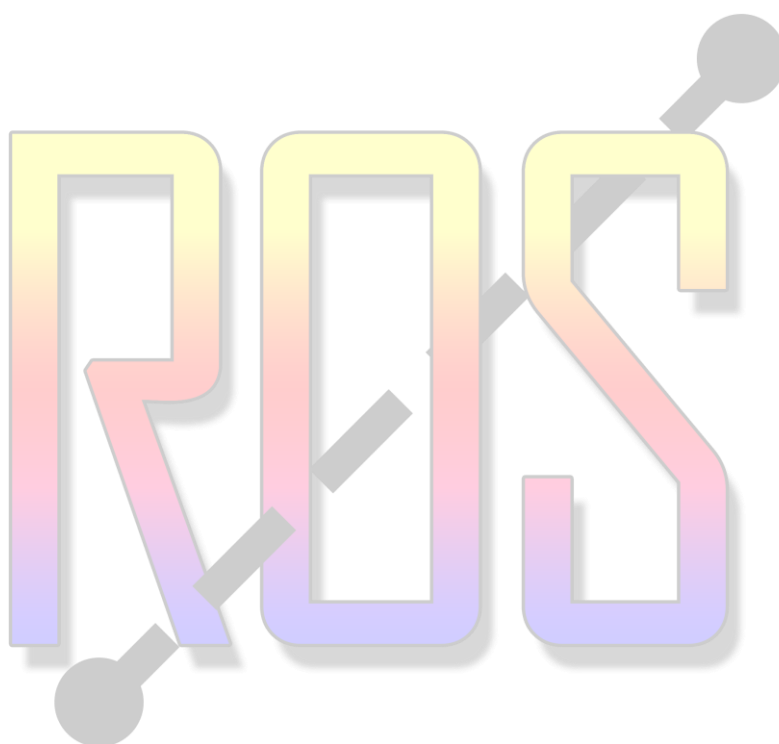


Fire ROS Calculator's Manual v. 2.0



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Introduction

This manual is made to guide the user through the Fire ROS Calculator to gain the desired results and highlight some of the algorithms and models that have been used in the program's code. The main objective of the Fire ROS Calculator is to measure the rate of spread of a fire spreading in a laboratory setting. The program calibrates a camera in a way that it obtains the real-world dimensions from the recorded images of a propagating fire (experiment). The program has some built-in tools to assist the user toward faster analysis. On this manual, the camera calibration process will be demonstrated first as it's the program's main core and it requires the user to perform a calibration procedure before performing the experiment. Secondly, the user's guide to perform an analysis and obtain the rate of spread of the fire and some subordinated results will be demonstrated. Finally, the assisting tools will be presented. The program's interface constructs from five tabs on the top, the first tab is "New Session" and it's used to perform new analysis. The rest of the tabs are: Load Session, Match Images, Extract Frames and Camera Calibration, these are the assisting tools that will be discussed later.

Camera Calibration

The used calibration algorithm is the Computer Vision System Toolbox™ calibration algorithm which uses the camera model proposed by Jean-Yves Bouguet [1]. The model includes: the pinhole camera model [2] and Lens distortion model [3]. The calibration algorithm uses a calibration object as reference which is checkerboard, this object will be captured by the camera in several positions. These captured digital (RGB) images of the calibration object will be used by the algorithm to calculate the camera parameters (extrinsic, intrinsic and lens distortion parameters). These parameters can be obtained using the Camera Calibration tool. These parameters are for the camera itself and the Camera Calibration tool allows the user to save them after being obtained for the first time. Please notice that you can use this saved camera parameters as long as you are using the same camera with the same lens.

In a case that the used camera in recording the fire propagation can't take normal digital images (an IR camera have been used). The camera parameters can't be obtained directly since the algorithm can detect the calibration object only on the normal digital (RGB) images. There will be a need to use another digital camera with similar characteristics. The other camera will be used to take photos of the calibration object and obtain the camera parameters where it will be assumed that the IR camera have the same obtained parameters. In this process the user must take into consideration the following:

- Place the digital camera as near as possible from the IR camera (or the camera that is being used to record the fire) and make sure that the two camera planes are parallel to each other (i.e. The

difference in position can be corrected by transferring one of them along the three axes (x y z) without any rotation)

- Use a digital camera that has a zoom and lens diameter close to the IR camera as much as possible.
- If the digital camera zoom is adjustable, then adjust it to be slightly lower than the IR camera (i.e. The captured frame on the IR camera will be within the digital camera frame)
- Before starting the analysis, the taken images of the calibration object from the digital camera must be cropped and rescaled to match the Images that will be taken from the recording of the fire. The Fire ROS Calculator is providing a tool (Match Images) to do that and its guide will be shown later. It's very recommended if the user is using some couple of cameras for the first time, to check the accuracy of the calibration using the Camera Calibration tool before starting the analysis.

The Program needs two inputs to perform the calibration and realize the real-world dimensions. First, the Obtained Camera Parameters of the used camera (the Camera Calibration tool section explains how to obtain it). Second, a Surface Reference Image, which is an image taken of the calibration object (checkerboard) while it's placed over (parallel) the surface where the fire is propagating. Please notice that if the fire on the experiment is propagating over more than one flat surface, you need to capture this Surface Reference Image for each of them and perform an analysis (program run) for each of them also.

A pre-analysis procedure is required during performing the experiment so the program can perform the calibration later. To Obtain the Camera Parameters the user needs to capture (photograph) the calibration object from 15 to 25 times where it will be placed in a different random position each time on the space around the surface where the experiment will be carried on. If the user is using the same camera, lens and calibration object size for a set of experiments, the user can perform this procedure to obtain the Camera Parameters only once and save it to be used for any other analysis later on. The Surface Reference image will need to be captured also during this pre-analysis procedure and it will be captured every time the position of the camera has changed. (I.e. As long as neither the position of the camera or the position of the fire propagating surface haven't changed the user doesn't need to capture the surface reference image for each performed test on this setting). Please notice the mentioned considerations on capturing the calibration object on the next section.

The algorithm constructs a 2D plan from the Surface Reference Image, where each point (pixel) on the image over this surface can be translated to a point on the constructed 2D real-world dimensions' plan.

On the next section, we will discuss the calibration object and the procedure of capturing it by the camera along with some considerations.

The Calibration Object

The calibration object is a checkerboard pattern. Where it constructs from black and white squares which have the same size distributed in a check pattern. This pattern will be printed on a board and used to calibrate the camera. The user may find a group of checkerboard patterns with different sizes ready to be printed from here:

https://github.com/AAbouali/Fire_ROS_Calculator/raw/Of15eeef92f857431374cf3d4646c5384a713388/calibration%20objects.rar

Considerations for constructing the checkerboard:

- The checkerboard must have an even number of squares along one side (e.g. X) and an odd number along the other side (Y) or vice versa.
- The checkerboard printout needs to be attached to a flat surface. Imperfections on the surface flatness can affect the accuracy of the calibration.
- We noticed that it's recommended to blur or smudge the border corners of the checkerboard that's attached to the edges of the board or otherwise an error might happen on the detection process. However, the provided patterns by us have this smudginess at the corners (Fig. 2).
- The user may consider only half the width or the height for the border squares as the shown pattern on Fig. 1. However, this is only to save from the total area as the far border corners are not detected.

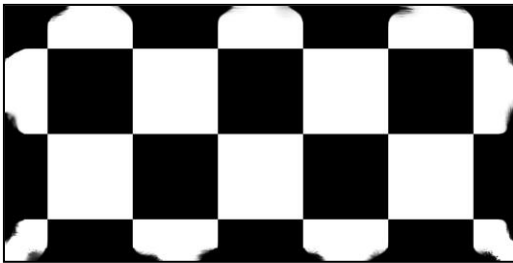


Fig. 2 Sample of the used checkerboard pattern to calibrate the camera

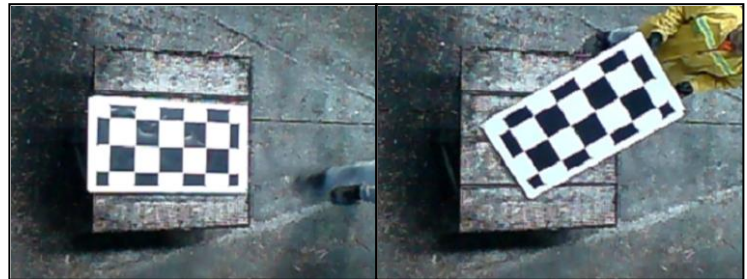


Fig. 1 Two different position where the calibration object where captured on. On the left, the board is place over the fire surface to get the Surface Reference Image. On the right, just a random position

Considerations for Capturing the Calibration Object:

- Keep the object in focus, and don't change it (do not use autofocus).
- Do not change zoom settings between images.
- Use a proper calibration object size that will fill about 20% of the camera frame. The smaller size it will fill, the less accurate the calibration will be or it will be invalid in some cases.
- Capture the images of the pattern at a distance roughly equal to the distance from your camera to the fuel bed surface. For example, if the fuel bed is at 2 meters, keep your pattern around 2 meters from the camera.
- Place the checkerboard at an angle over the three axes less than 45 degrees relative to the camera plane.

Camera Calibration Tool

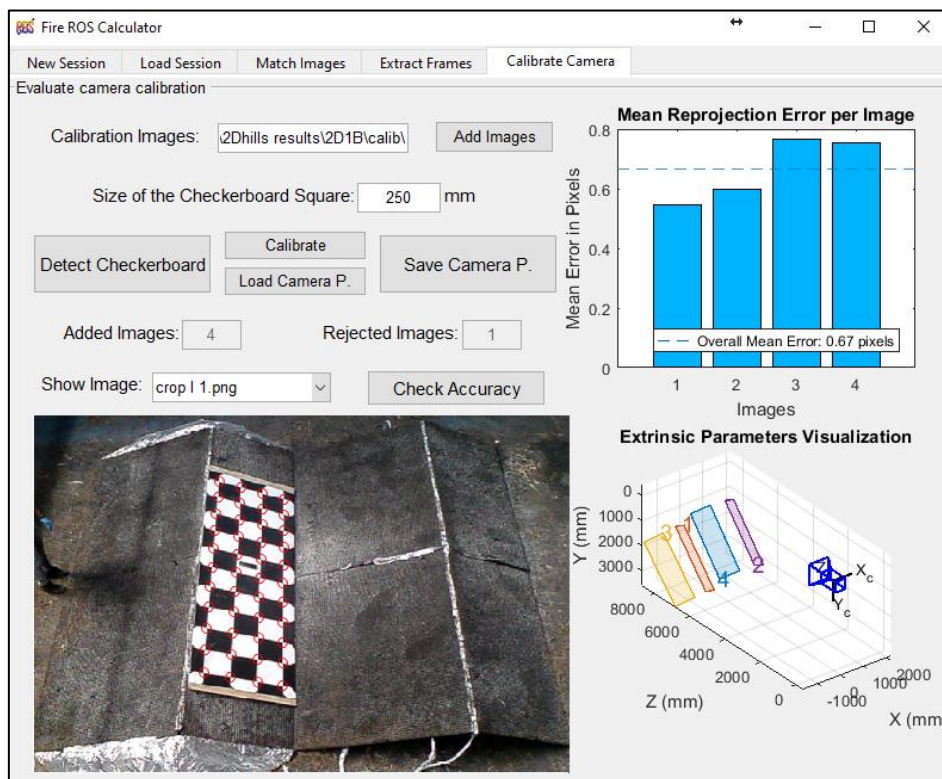
The Camera Calibration Tool performs two main functions, Obtaining the camera parameters and check the accuracy of a calibration.

Obtaining the Camera Parameters:

To obtain the camera parameters for a camera, it's required to have at least 4 images showing the calibration object in different random positions. After having these calibration images, follow the following steps to obtain the camera parameters:

- Select the calibration images on the top

- Enter the size of one of the squares (the length of one edge of the square) that are constructing the checkerboard pattern
- Click on “Detect Checkerboard” button. After the program finish detecting the checkerboard (the corners of the squares) on the inputted images, the images will be displayed on the bottom with the detection of the corners plotted over it. Some of the images could be rejected if it's violating any of the mentioned consideration before on capturing the calibration object. The number of accepted and rejected images will be displayed. The drop-down menu over the displayed image shows only the accepted images and the user can change the selection to display another image with the detection on it. Notice that the algorithm detects only the inside corners on the board without its borders, that's why the smudginess has been added to the borders of the board to insure that the program, won't detect the corners at the borders. The user might need in some cases to edit the calibration images by blurring or smudging the borders of the board in a case that the program has mistakenly detected some of these corners.
- If the accepted images are over 3, the user can obtain the camera parameters by clicking over “Calibrate”. After the program finish, the mean reprojection errors and the extrinsic parameters visualization will be displayed. The reprojection errors are the mean difference in pixel between the detected location of the corners and the calculated location by the algorithm. This error could be high for some images if the board wasn't flat and it's better to exclude this particular image and repeat the process. The extrinsic parameters' visualization plot shows the locations of the calibration object relative to the camera where the camera is at the origin. The user can rotate this plot for better display.
- Finally click on “Save Camera P.” To save this obtained camera parameters in order to use it later for analysis. It's recommended to save it to the default folder location where all the saved camera parameters files in this folder are displayed on the drop-down menu of the camera parameters selection on the New Session tab.



To check the accuracy of a calibration or precisely, the accuracy of measuring the real-world dimensions, follow the following steps:

- First, you need to obtain a camera parameters following the previous shown steps or you can load a saved one in a case that there is less than 4 images taken of the calibration object from the same camera position there for it's not possible to obtain the camera parameters. Or simply, you already have the camera parameters of the used camera and you just want to check the accuracy of the current detection of the current surface.
- Select the surface reference image from the drop-down menu of the accepted images. The constructed 2D plane will be based on the position of the calibration object on the currently displayed image.
- Click on "Check Accuracy". A window will be displayed showing the Surface Reference image. You will need to place a line over this image by right-clicking over the image and choose "Add Line". Then enter the real distance of this line and click "Calculate Accuracy". The error in this calculated distance will be displayed which is calculated according to the following equation:

$$error(\%) = abs \left(\frac{calculated\ Dist. - real\ Dist.}{real\ Dist.} \right) * 100 \quad (Eq1)$$

The user may change the image that the distance is measured from. (E.g. Selecting an IR image). But the user must be sure that the selecting image has the same size and resolution as the surface reference image and have been captured from the same camera position.

User's Guide

The program interface is constructed of single window with five tabs, which are:

New Session; which is used to start a new analysis.

Load Session; which is used in a case that you have an old analysis and you need to gain more results.

Match Images; an assistant tool to equalize the size and resolution of a group of images to match another one.

Extract Frames; an assistant tool to extract frames automatically from a video with a constant time step between them.

Calibrate Camera; a tool to obtain the camera parameters and to check the accuracy of the calibration.

Each tab is a program that runs independently from the others. In the following, a detailed guide of how to use each of them except the Camera Calibration tool which it was demonstrated previously.

1. New Session (Analysis)

On the New Session tab, you can find the window is divided into two panels, one for the inputs, and another for the results that will be used after detecting the fire front.

1.1. Inputs

There are six groups of inputs must be provided before starting the process of detecting the fire front. These groups are:

1.1.1. Session Name

On the field where it's written "Session Name", provide a name for this analysis.

1.1.2. Camera Parameters

You can select a saved camera parameters file from the drop-down menu if it was saved in the default folder or select "Load Calibration" and choose the file. To create the camera parameters file for some camera, use the Camera Calibration Tool.

1.1.3. Images

Fire Front images: which is a series of images (frames) showing the propagation of the fire front over a surface with the time. The time step between them can be variable or fixed.

The selected images will be sorted by their names in ascending order, where the first image will have the zero-time reference. So, the user must check before selecting the fire front images as an input that their names are ordered as the same as their timing order.

Surface Reference Image: which is the image capturing the calibration object placed over the fire propagating surface.

Look the Camera Calibration part for more details about the Surface Reference image and the Camera Parameters

1.1.4. Size of the Checkerboard Square

In this field, enter the length of one square of the checkerboard (the calibration object) that was used to get the Surface Reference Image in mm.

1.1.5. Time Laps

The time lap is the time between the images of the fire front (the frames) that are showing the fire propagation with time. Select an option, depending on the time lap between these frames if it was fixed or variable (changing from frame to another). If you have variable time steps between the frames, you need to enter the time between each two frames on the field that will appear by clicking on "Add Laps". The times are given in seconds.

1.1.6. Fuel Bed Geometry

Here you will need to provide the shape of the surface where the fire was propagating (the fuel bed). In other terms, the area within this shape will be the region of interest (ROI) during the analysis. You have two standard shape options which are the Rectangle, Triangle. If the shape is not one of them you need to draw the shape manually.

On the following a description on how to detect the bed's location on the images if it was one of the standard shapes or how to draw the shape if it's not:

Rectangular

To detect the location of this rectangular area on the images, you must draw one edge of the bed and provide its length and the length of the perpendicular edge to it (the joint edge).

To draw the edge, click on "Detect Bed Location" then choose one of the fire front images or the surface reference image to draw a line over one of the bed edges. To draw the line, click with the mouse where the edge is starting and drag the mouse while holding to detect the other end of the edge. You can edit the location of the ends of the line by dragging them. After placing the line at the desired position, double click over the line to end the process of detection or click "Enter".

Triangular

To detect the location of this triangular area on the images, you must draw one edge of the bed and provide its length. Also, the length of another edge on the triangle (the joint edge) and the angle between it and the drawn edge must be provided. The drawing has the same procedure as for the rectangular shape, but an attention must be taken with defining the ends of the drawn line, where the defined joint edge will join the drawn edge at its second defined end (last detected point).

Drawing the shape Manually

You can draw manually any shape with straight edges using this option. To draw the shape, click on “Draw Shape Manually”. You will need to select an image first where you will draw the shape over it and provide the number of edges that’s the shape has. To draw the lines (the shape’s edges), right-click over the image and select “Add Lines”, then draw them line by line. Note that once you finished placing a line of them, you will be enabled automatically to place the next one and so on, only after finishing placing all the lines, you can edit their location before pressing “OK” to end the process.

1.1.7. Saving the frames

By checking the box of “Save frames with fire front lines” the program will save a copy of the fire front images where the fire front lines are drawn over these images. The option is useful in a case the fire is propagating over more than one surface, which means several runs of the program, so by this option the user can use these saved images as the Fire Front Images for the next run. That will make it clear where the fire front was detected in the run before.

Finally, you will need to select a folder as a directory where all the results will be saved in.

1.1.8. Detection of the fire front

Two methods are available to detect the fire front location on the frames, an automatic and a manual method. By selecting one of these two options after entering all the inputs, the program will run.

Manual Fire Front Detection

The program will open the fire front images automatically one after another, where the user must detect the fire front on each one of them. The fire front can be detected by drawing small line segments which will be defined by detecting the starting and ending points of each line segment. Every ending point will be considered the starting point of the next line automatically. In the following some instructions to draw the lines:

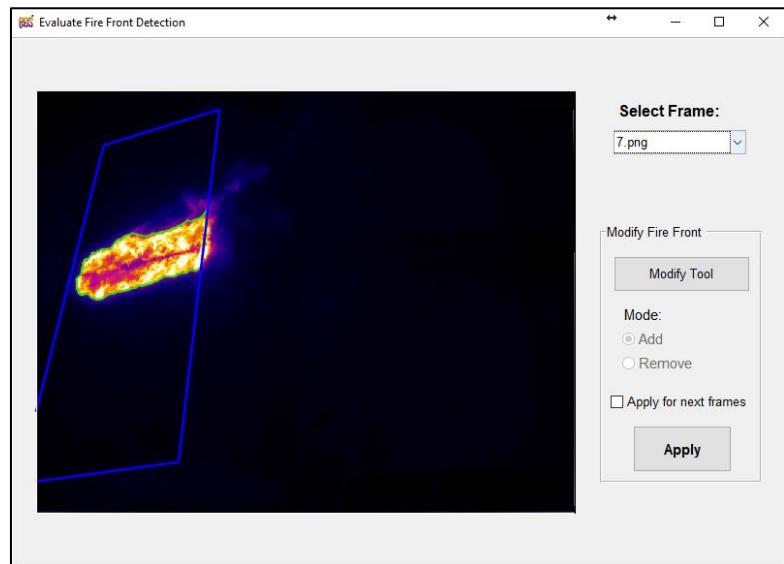
- To add a point; click a left-mouse-click to detect a new point location.
- To delete the last detected point; press the “Backspace” key.
- To finish the detection for the current frame; click double clicks by the mouse while detecting the last point, or simply you can press “Enter”.

Automatic Fire Front Detection

This method is based on an image processing algorithm that detects the fire front line on each frame automatically. The algorithm depends on the image colors where the burned area is usually brighter and on the history of the fire front location on the previous frames. It's very recommended to use IR camera to record the fire where this method will work the best. The user might need to change the detection sensitivity, the default value is 0.5, this value can be changed between 0 and 1. Decreasing the detection sensitivity will include more brighter areas within the burned area, then increasing the fire parameter and vice versa with increasing the sensitivity. After the program finishes the detection, the user may check the detection on each frame by clicking on "Evaluate Fire Fronts Detection" on the right panel. However, this algorithm has a limitation, which is can't detect two different burned areas on the same ROI, in fact, when the algorithm detects two areas it calculates their area and consider only the bigger one. The program will send a warning to the user if more than one burned area has been detected.

1.1.9. Evaluate Fire Fronts Detection

This tool allows the user to evaluate the automatic detection of the fire front on each frame and modify it if needed. Select the frame from the drop-down menu to be displayed, you can notice that the green line is the fire parameter or the fire front, the blue line is the ROI where the program is detecting the fire parameter only within it. To modify the fire parameter on the displayed frame, follow these steps:



- Click "Modify Tool" and go over the image and draw an area parameter by clicking and dragging. After drawing the area, you can change its location by dragging it. You must insure that the drawn area and the burned area are intersecting.
- Choose a mode either Add or Remove. The Add mode will add the drawn area parameter to the burned area and redraw the overall fire parameter, the Remove mode will exclude the drawn area.
- Check the box "Apply for next frames" if you need to apply the same modification to all the following frames of the currently displayed frame.
- Click "Apply" to execute the modification.

After entering all the inputs and detecting the fire front. The result options on the right panel will be enabled to get any of them.

Once the program finishes the process of fire front detection, it will save a file with extension *.mat, this file has all the necessary data to load the session and get any other results later using “load Session” tab.

1.2. Results

On the results panel, there are different options to measure the fire’s ROS or to represent it. In the following we will discuss each of them.

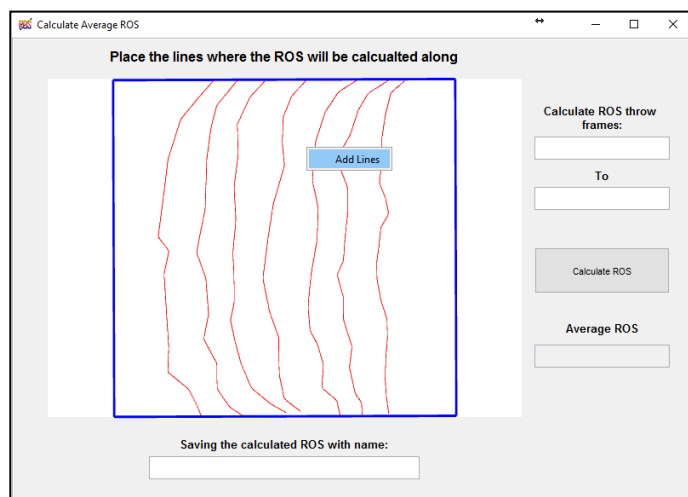
Please notice that all the output results during the session are saved on the memory. After finishing the analysis, the results can be saved in an Excel sheet by clicking over “Save Excel” on the right down corner. It’s important to press the “Save Excel” button before exiting or resting or the gained results will be lost. The excel sheet includes also some information about the session and the inputted data.

1.2.1. Calculate Average ROS

We define the average rate of spread (ROS) of a fire along a prescribed direction as the slope of a linear fit of the function: $D(t)$, where D is the distance passed by the fire along the predefined direction during a time (t) . We are following on this Viegas 2004 [2]. However, This simplification to calculate the average ROS is only acceptable if there are no consistent variations of the rate of spread (ROS) and it implies that the fire is spreading in a quasi-steady-state, which may not be valid in all cases (Viegas 2004) [2]. In case there are consistent variations, we recommend to use

also the “Calculate Dynamic ROS” option to see these variations. The slope is calculated considering the passed distances on the Y axis and their corresponding times on the X axis. For calculating the average ROS of the fire in a general direction, the program gives you the ability to add several lines where it will calculate the average ROS along each one of them and the average of all of them. The user may use several adjacent lines to avoid local effects and variations on the fire spread behavior along some direction.

To place the lines that the ROS will be calculated along them, click a left-mouse-click over the presented fire propagation contour map and select “Add Line”, then you can place the lines over the map after entering how many lines you would like to add. The user needs to define which frames will be considered in this calculation by adding two frame ranks (from ... to...), the first number (from) will be considered the first frame and the second number (To) will be the last frame to calculate along. These two frame ranks will change their colors to green on the contour map. Once the ROS was calculated, the program saves an image on the results directory of the fire propagation map and the lines placed over it. Please notice the following:

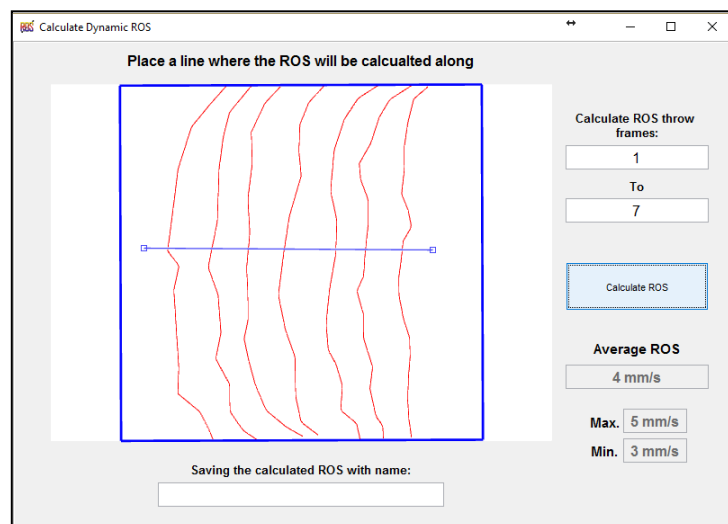


- Once you finish placing a line you will be enabled to place the next one and so on, only after finishing placing all of them on the map, you can edit their location before pressing “Calculate ROS” by dragging their ends on the map.
- The user must insure that the placed lines are intersecting with the all considered fire front lines (frames) that was entered before. In a case that it didn’t, the program will give an error.

1.2.2. Calculate Dynamic ROS

We define the dynamic ROS as the passed distance from frame to another divided by the time consumed to pass it ($\Delta D / \Delta t$) along a predefined direction. Or in other terms, it’s the slope of the line joining two following points on the $D(t)$ plot. So, by calculating this ROS you will have the ROS that the fire has translated with between each two following frames.

To measure the dynamic ROS, you will need to place a line by left-mouse-clicking over the displayed fire propagation contour map and select “Add Line”. This line is where the ROS will be calculated along it. As mentioned on Calculating Average ROS before, the user must enter the first and last frame ranks where this ROS will be calculated between.



For this option, the program provides the passed distances between the frames and the ROS that the fire translated with between them (the dynamic ROS), along also with the average ROS. However, on the window only the Average ROS and the maximum and minimum achieved ROS’s are presented. The detailed results can be found on the Excel sheet later.

1.2.3. Measuring distances

This option allows the user to measure any linear distance over the fuel bed surface either by detecting it on the contour map or from an image that the user would choose.

To measure the distance, you can just place a line or more depends on how many distances you like to measure. Adding the lines can be made with the same method that was explained for calculating the average ROS on section 1.2.1.

The obtained results from this option is the measured distances and the average of them in a case there was more than one.

1.2.4. Build the fire propagation map

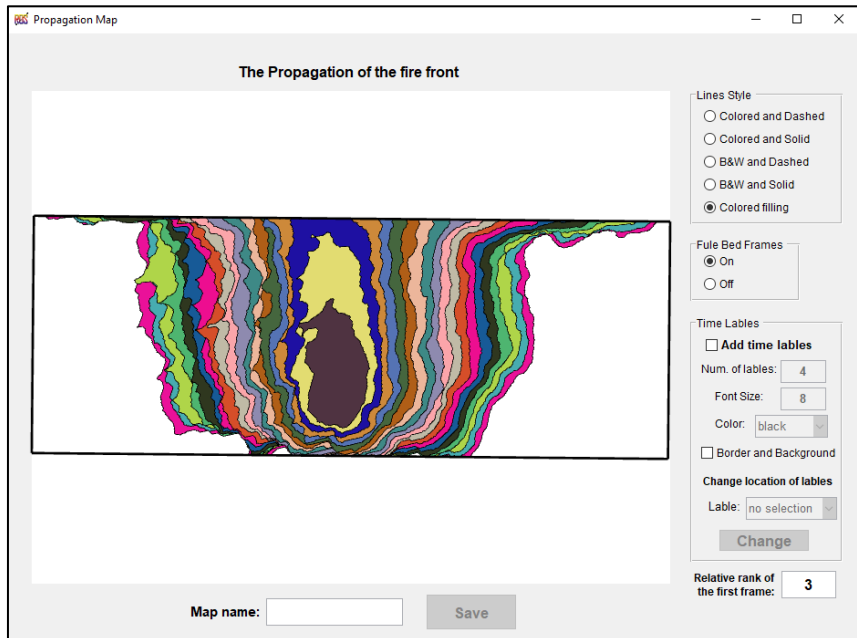
This tool helps the user to build a customized fire propagation contour map according to his needs. There are several options like showing or hiding the bed frame, changing the style of the lines and add time labels on the map.

If your experiment requires several program runs (more than one surface), there is an option that you can

determine the rank of the first frame on this map relative to the whole experiment. This will make consistency in the style of the map between the different runs. (i.e. the same color for the same time step on all the generated maps).

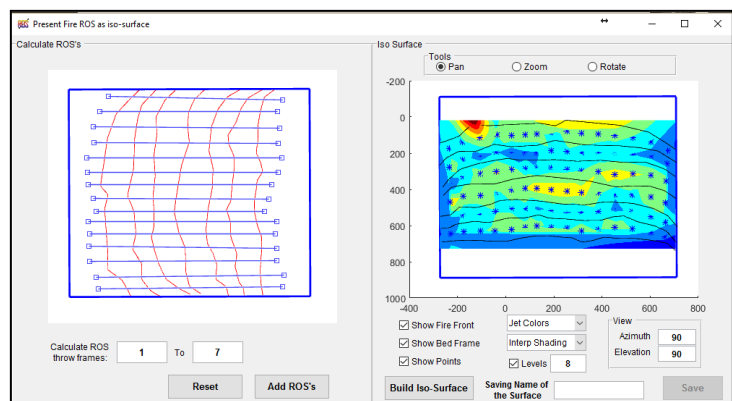
The program place the time labels randomly over the fire perimeter. To change the location of the time label, select it from the drop-down menu Label and click over change, you will notice that the fire parameter that the label is associated to will change its color to red. Now you can choose its new location over that parameter by click on it.

After adjusting the map style, enter a name where it will be saved with and click Save. Please notice that if you saved two maps with the same name, it will overwrite it automatically.



1.2.5. Build iso-surface from ROS's

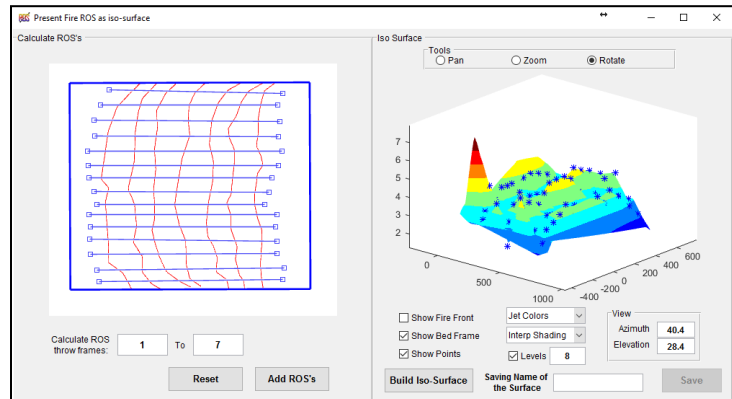
This Tool allows the user to do a 3D presentation of the fire ROS's with their X-Y location over the fire surface, where the Z axis represents the dynamic ROS. To get the iso-surface the user must add at least one line where the dynamic ROS will be calculated along it. However, to get a good



presentation of the change on the fire ROS over the surface, it's recommended to use a convenient number of lines covering the whole surface, so the 3D representation will have enough values to interpolate and construct a good representing iso-surface.

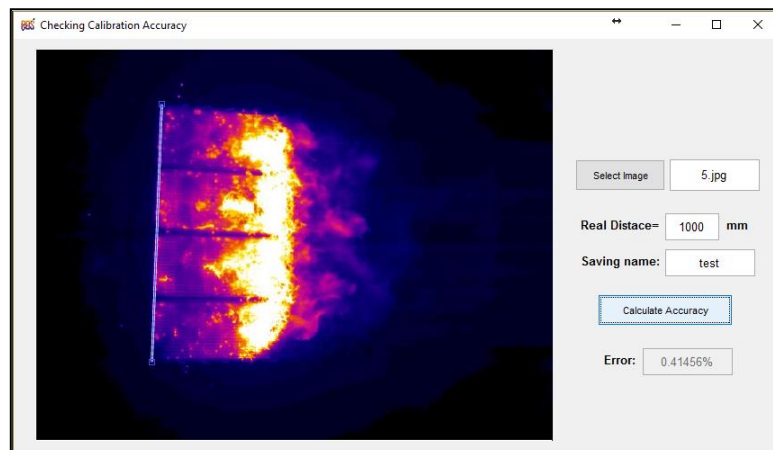
To add the lines, use the same method that's mentioned in section 1.2.1. You can add more than one group of lines where every group will have different range of frames. Noticing that each group of lines must intersect with all the specified frames. After placing some group of lines, you must click "Add ROS's" before drawing another group or to build the iso-surface.

After finishing adding ROS's values, click on "Build iso-surface" button. The user can change the style of the plot through several presented options.



1.2.6. Checking Accuracy

You can check the accuracy of the output results through this tool. The check is done through checking the accuracy of a measured distance as measuring the real-world distances is the main key on all the results. So, the presented error here can be assumed as the error in all the obtained results for this session.



To measure the error in a distance measurement, you need to select an image where you want to measure this distance from, then place a line over it with the same way that was shown in section 1.2.1. Enter the real distance of that measurement and the program will give you the error calculated according to Eq1. However, it's recommended to take several measurements and take the average of them, as this error is including also the human error on placing the line exactly over the length that's being measured. Also, the error might change from direction to another.

2. Loading Session

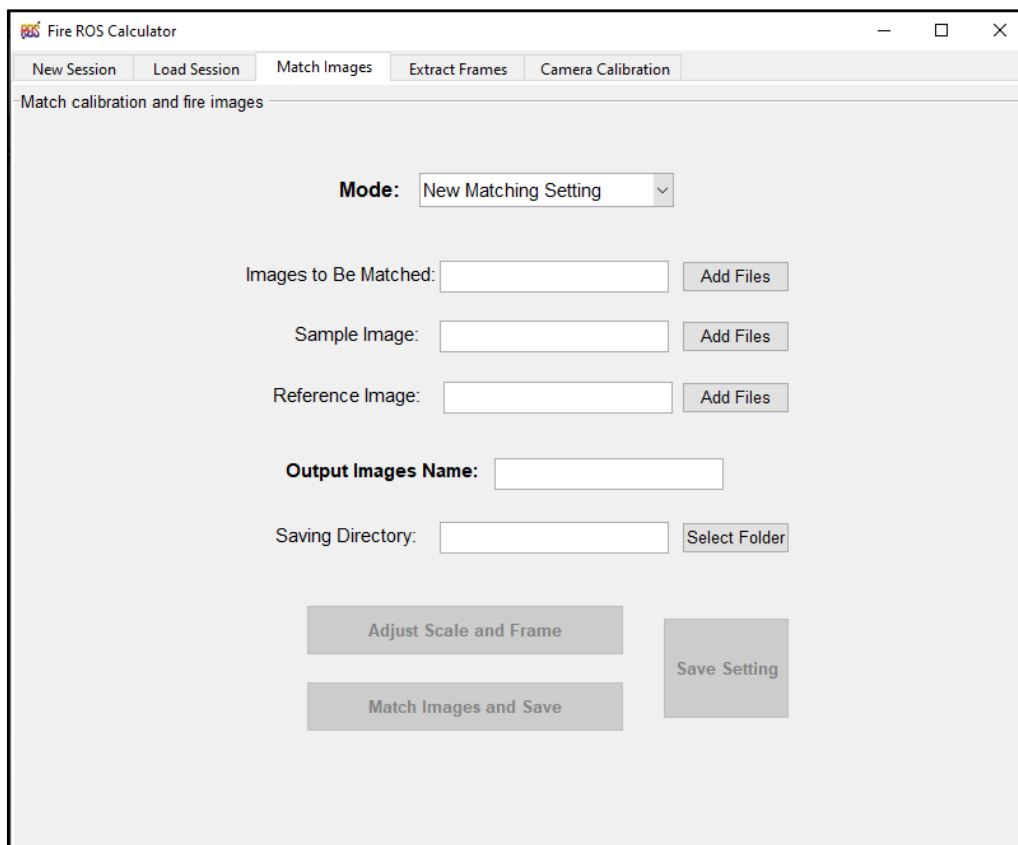
From this tool, the user can load an old session file (analysis), which is a file have the extension *.mat (a MATLAB Workspace), this file is generated automatically after performing the fire front detection. By loading the session file and choosing a directory and a name for the new results (the excel sheet name), the user will be able to obtain any of the result options that were mentioned before in section 1.2.

The program doesn't save the results in the session file neither on this tool or when the session file was created. Notice during saving any file, if the program found a file with the same name in the saving directory, it will overwrite it.

The screenshot shows the 'Fire ROS Calculator' application window. It has a menu bar with 'New Session', 'Load Session', 'Match Images', 'Extract Frames', and 'Camera Calibration'. The 'Load Session' tab is active. The interface is divided into two main panels: 'Load Project' on the left and 'Results' on the right. In the 'Load Project' panel, there are three input fields: 'Select Session:' with a text box and a 'Load' button, 'Results Directory:' with a text box and a 'Select Folder' button, and 'New Session Name:' with a text box. The 'Results' panel has a 'Total No. of Frames:' input field at the top. Below it, under the heading 'Results:', there are six buttons: 'Calculate Average ROS', 'Calculate Dynamic ROS', 'Measure Distances', 'Build the Fire Propagation Map', 'Build iso-surface From ROS's', and 'Check Clibration Accuracy'. At the bottom right of the 'Results' panel is a 'Save Excel' button.

3. Match Images

This assisting tool is used to resize a group of images to match another inputted reference image. The tool is useful in a case that the fire images had a different size than the Surface Reference Image. Two options are available here, a New Matching Setting, where the user needs to define the resizing scale and frame, or to Load a Matching Setting, where the user can apply the same resizing ratio that was saved before to another group of images without redefining them.



The screenshot shows the 'Match Images' window of the 'Fire ROS Calculator' application. The window has a title bar with standard OS controls and a tabbed interface with tabs for 'New Session', 'Load Session', 'Match Images' (which is active), 'Extract Frames', and 'Camera Calibration'. Below the tabs, the window title is 'Match calibration and fire images'. The main area contains the following controls:

- Mode:** A dropdown menu currently set to 'New Matching Setting'.
- Images to Be Matched:** A text input field followed by an 'Add Files' button.
- Sample Image:** A text input field followed by an 'Add Files' button.
- Reference Image:** A text input field followed by an 'Add Files' button.
- Output Images Name:** A text input field.
- Saving Directory:** A text input field followed by a 'Select Folder' button.
- Buttons:** At the bottom, there are three buttons: 'Adjust Scale and Frame', 'Match Images and Save', and 'Save Setting'.

3.1. New Matching Setting

To match a group of Images to another Image (make them equal on the size and frame), add the Images (can be only one image) at "Images to be Matched" and add the image that you want to match them to it at "Reference Image". At the "Sample Image" you need to select one of the added images to be matched (the same image if it's only one). This sample image will be used to define the required scale and frame to match the images. Finally, enter a prefix name for the output images and their directory.

To Resize the images, the user must define a few points on the Sample Image and define the same location of these points on the other image (the Reference Image). Click over "Adjust Scale and Frame", the Reference Image will be displayed, pinpoint two points on this image. Then the Sample Image will be displayed, pinpoint the same location of the two points on it. The two points must be pointed out as accurate as possible since it will affect the matching accuracy. (e.g. pinpoint two corners of the fuel bed appearing in both images). This Process will adjust the resolution of

both images. Then, the program will open again the Reference Image where you need to pinpoint one point this time and pinpoint it also on the other image (The Sample Image). This process will define the image frame.

Now click over “Match images and Save” to execute the defined resizing process to the images and save them. The user may save also this matching setting where it can be used later to resize another group of images without repeating the process of defining the points.

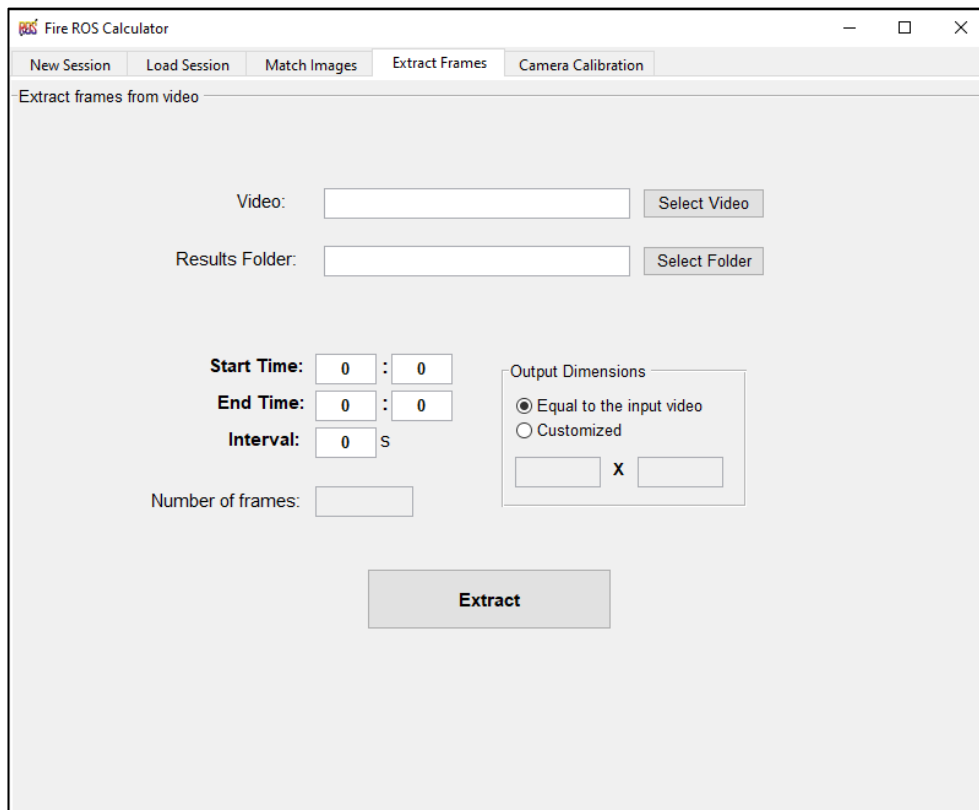
3.2. Load a Matching setting

The user may use this option if there is a saved matching setting and wants to apply it to a group of images. Notice that the Images to be matched must have the same resolution and frames as the images that were used to create the Matching setting file to give the same desired output images.

To perform that, just add the images and enter a prefix name and a directory for the output images, then click over “Match images and Save”.

4. Extract Frames

The Extract Frames tool is helping the user to extract frames from an inputted video automatically with a constant time step between them. It was developed to obtain the frames that will be inputted on the analysis of the fire's ROS. However, it can be used for any purpose. The inputted video can have the format of .mp4, .mov or any format supported by Microsoft Media Foundation (.wmv, .avi, etc. ...).



The screenshot shows the 'Fire ROS Calculator' application window with the 'Extract Frames' tab selected. The window contains the following fields and controls:

- Video:** A text input field followed by a 'Select Video' button.
- Results Folder:** A text input field followed by a 'Select Folder' button.
- Start Time:** Two input fields for minutes and seconds, both set to 0.
- End Time:** Two input fields for minutes and seconds, both set to 0.
- Interval:** An input field set to 0, followed by a unit 's' for seconds.
- Number of frames:** An empty input field.
- Output Dimensions:** A section with two radio buttons: 'Equal to the input video' (selected) and 'Customized'. Below the radio buttons are two input fields for width and height, separated by an 'x'.
- Extract:** A large button at the bottom center of the window.

To extract frames from a video, select the video and a directory where the output images will be saved in. Then, enter the start and end times where the extraction will start and end in the format min:sec. The user must make sure that these times are within the video duration or the program will give an error. Enter the desired interval between the frames in seconds. The output number of frames will be displayed once you finish inputting all the time information and will be updated if you updated any of them. The user may also specify the resolution of the output images. After finish inputting the data, click over "Extract" to save the frames in the specified directory.

Debugging and Feedback

This program has been developed recently and it's still under development. Please check that you have the latest version of the program where you can find it on the GitHub Repository: https://github.com/AAbouali/Fire_ROS_Calculator

This program has been tested and validated before publishing it, the user may find a validation package in the same repository. Although, errors might happen, the developer asks you to please send the log file when an error will happen to this email: awabuali@hotmail.com along with a brief description of the scenario when it happened. The log file can be found on the same directory that the program was launched from under the name "Fire_ROS_LogFile".

References

[1] Bouguet, J. Y. "Camera Calibration Toolbox for Matlab." *Computational Vision at the California Institute of Technology*.

[2] Viegas, Domingos X. (2004). "Slope and Wind Effects on Fire Propagation." *International Journal of Wildland Fire* 13 (2): 143–56. doi:10.1071/WF03046.

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