Quality Report

Generated with Pix4Dmapper Pro version 4.2.27

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	eldo_4k_3_x3
Processed	2018-08-23 12:48:12
Camera Model Name(s)	FC350_3.6_4000x3000 (RGB)
Average Ground Sampling Distance (GSD)	4.64 cm / 1.83 in
Area Covered	0.589 km^2 / 58.8847 ha / 0.23 sq. mi. / 145.5827 acres
Time for Initial Processing (without report)	02h:33m:53s

Quality Check

Images	median of 13360 keypoints per image	✓
Dataset	1947 out of 1965 images calibrated (99%), all images enabled, 5 blocks	⚠
Camera Optimization	2.79% relative difference between initial and optimized internal camera parameters	✓
Matching	median of 887.146 matches per calibrated image	⚠
Georeferencing	yes, no 3D GCP	⚠

Preview

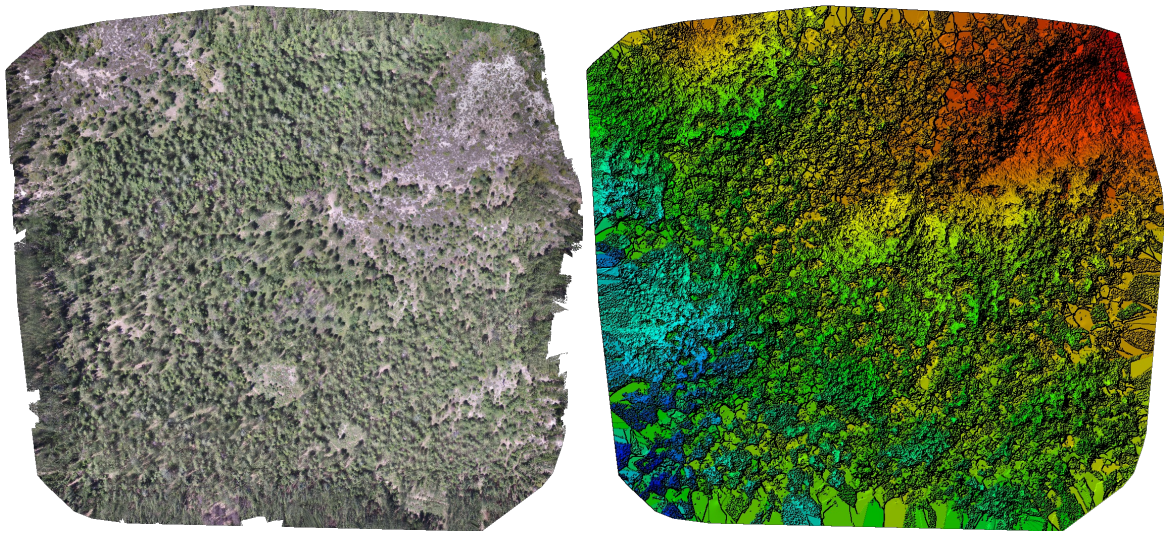


Figure 1: Orthomosaic and the corresponding sparse Digital Surface Model (DSM) before densification.

Calibration Details

Number of Calibrated Images	1947 out of 1965
Number of Geolocated Images	1965 out of 1965

Initial Image Positions

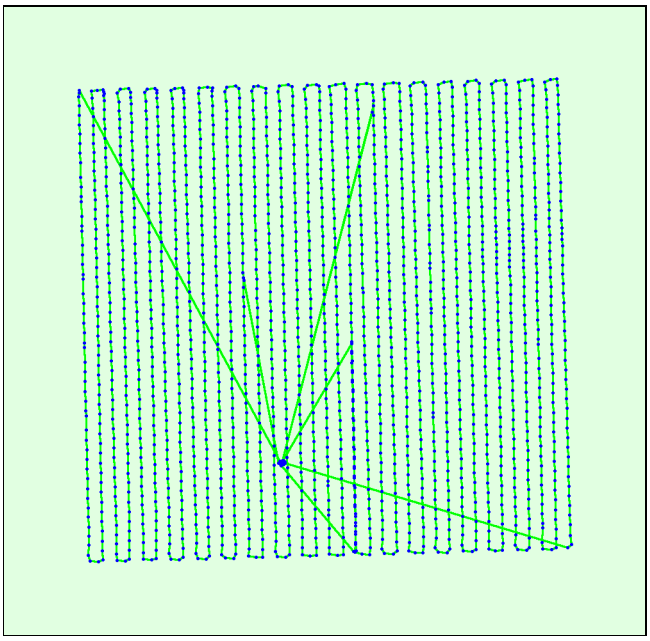
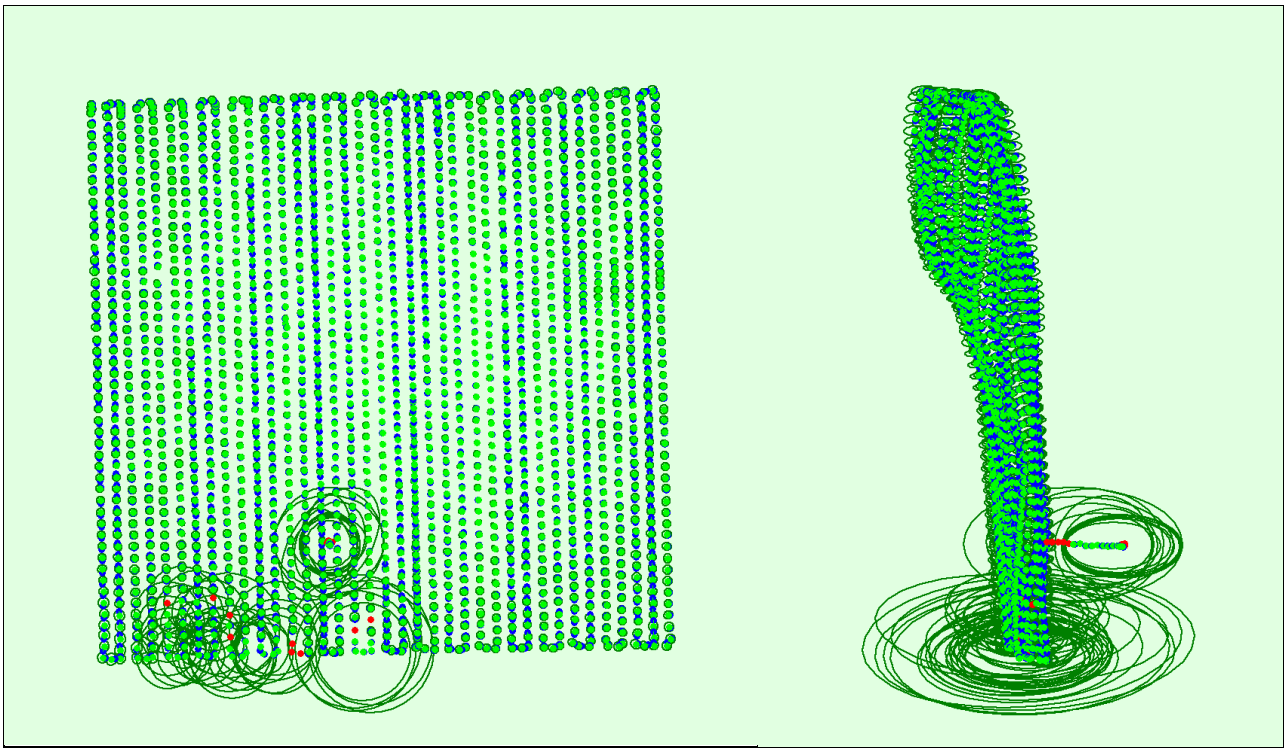
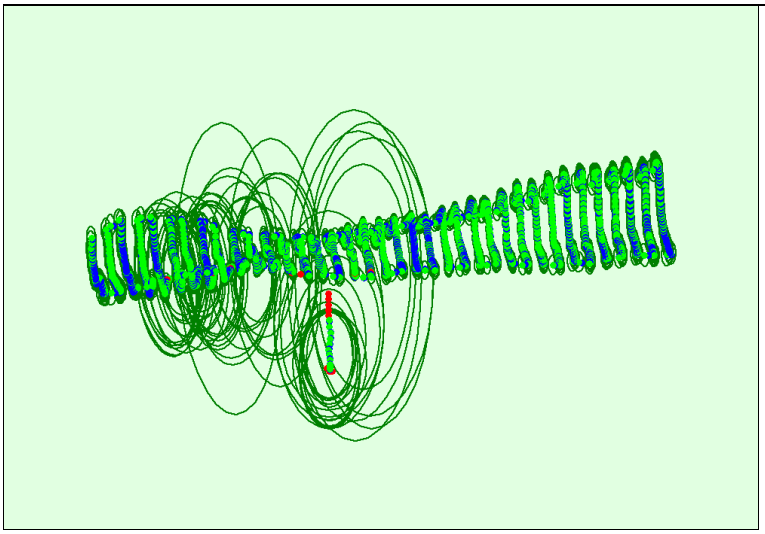


Figure 2: Top view of the initial image position. The green line follows the position of the images in time starting from the large blue dot.

Computed Image/GCPs/Manual Tie Points Positions





Uncertainty ellipses 50x magnified

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	0.096	0.097	0.207	0.430	0.492	0.173
Sigma	0.124	0.127	0.279	3.291	3.913	1.376

Overlap

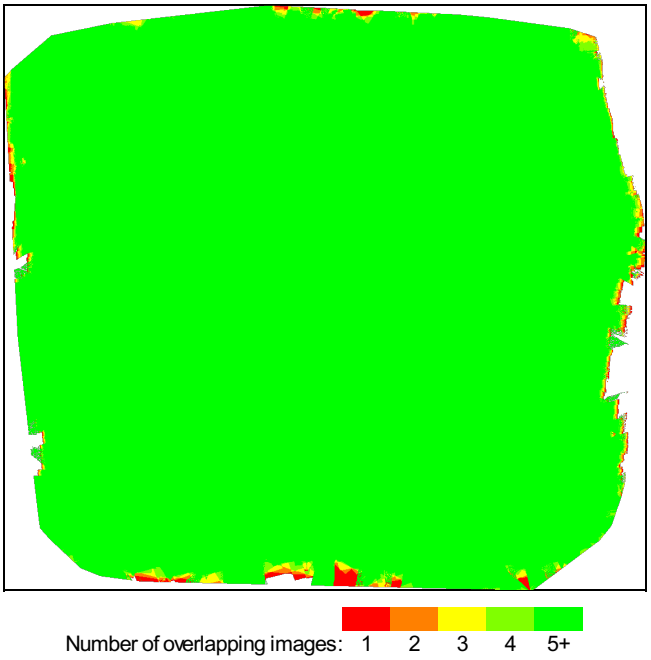


**Figure 4: Number of overlapping images computed for each pixel of the orthomosaic.
Red and yellow areas indicate low overlap for which poor results may be generated. Green areas indicate an overlap of over 5 images for every pixel. Good quality results will be generated as long as the number of keypoint 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	2292228
Number of 3D Points for Bundle Block Adjustment	767627

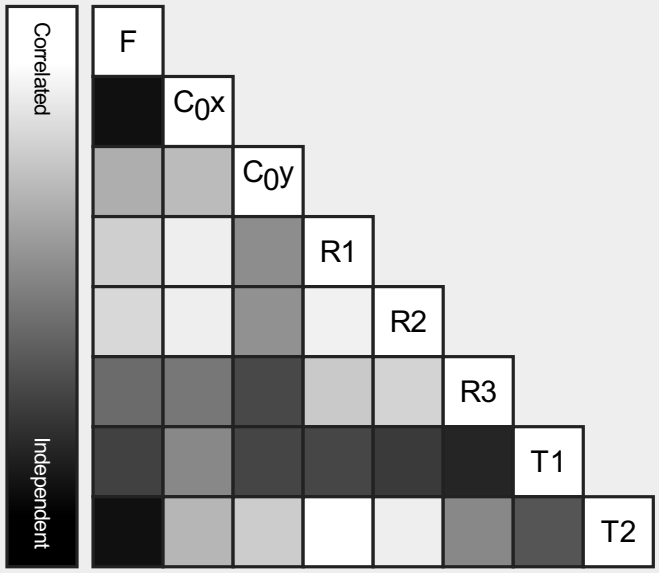
Mean Reprojection Error [pixels]	0.122

Internal Camera Parameters

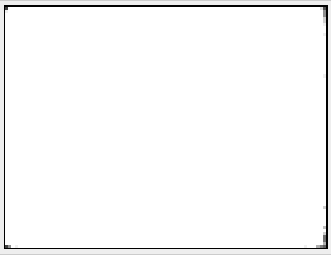
FC350_3.6_4000x3000 (RGB). Sensor Dimensions: 6.317 [mm] x 4.738 [mm]

EXIF ID: FC350_3.6_4000x3000

	Focal Length	Principal Point x	Principal Point y	R1	R2	R3	T1	T2
Initial Values	2285.722 [pixel] 3.610 [mm]	2000.006 [pixel] 3.159 [mm]	1500.003 [pixel] 2.369 [mm]	-0.130	0.106	-0.016	-0.000	0.000
Optimized Values	2349.510 [pixel] 3.711 [mm]	1986.300 [pixel] 3.137 [mm]	1502.282 [pixel] 2.373 [mm]	-0.131	0.116	-0.015	0.001	0.000
Uncertainties (Sigma)	1.428 [pixel] 0.002 [mm]	0.042 [pixel] 0.000 [mm]	0.049 [pixel] 0.000 [mm]	0.000	0.000	0.000	0.000	0.000



The correlation between camera internal parameters determined by the bundle adjustment. White indicates a full correlation between the parameters, ie. any change in one can be fully compensated by the other. Black indicates that the parameter is completely independent, and is not affected by other parameters.



The number of Automatic Tie Points (ATPs) per pixel, averaged over all images of the camera model, is color coded between black and white. White indicates that, on average, more than 16 ATPs have been extracted at the pixel location. Black indicates that, on average, 0 ATPs have been extracted at the pixel location. Click on the image to the see the average direction and magnitude of the re-projection error for each pixel. Note that the vectors are scaled for better visualization. The scale bar indicates the magnitude of 1 pixel error.

2D Keypoints Table

	Number of 2D Keypoints per Image	Number of Matched 2D Keypoints per Image
Median	13360	887
Min	10184	52
Max	20236	5942
Mean	13395	1177

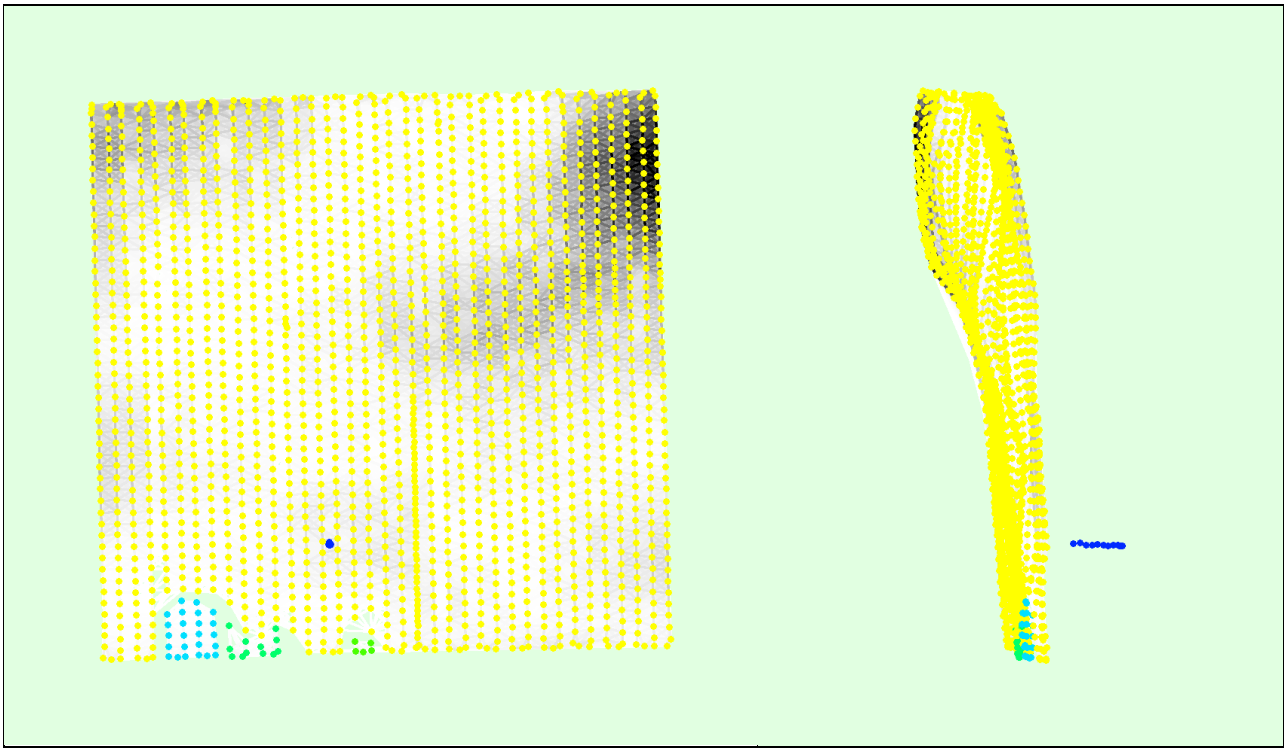
3D Points from 2D Keypoint Matches

	Number of 3D Points Observed
In 2 Images	521908
In 3 Images	119300
In 4 Images	48300
In 5 Images	24450
In 6 Images	14172
In 7 Images	9393

In 8 Images	6368
In 9 Images	4480
In 10 Images	3352
In 11 Images	2535
In 12 Images	1999
In 13 Images	1580
In 14 Images	1195
In 15 Images	1048
In 16 Images	887
In 17 Images	730
In 18 Images	639
In 19 Images	554
In 20 Images	486
In 21 Images	417
In 22 Images	369
In 23 Images	307
In 24 Images	287
In 25 Images	267
In 26 Images	208
In 27 Images	194
In 28 Images	194
In 29 Images	144
In 30 Images	141
In 31 Images	128
In 32 Images	110
In 33 Images	91
In 34 Images	117
In 35 Images	92
In 36 Images	81
In 37 Images	69
In 38 Images	58
In 39 Images	73
In 40 Images	54
In 41 Images	73
In 42 Images	66
In 43 Images	50
In 44 Images	42
In 45 Images	35
In 46 Images	67
In 47 Images	49
In 48 Images	42
In 49 Images	35
In 50 Images	37
In 51 Images	35
In 52 Images	25
In 53 Images	17
In 54 Images	20
In 55 Images	29
In 56 Images	17
In 57 Images	17
In 58 Images	9
In 59 Images	16
In 60 Images	13
In 61 Images	11
In 62 Images	15
In 63 Images	12
In 64 Images	14
In 65 Images	8
In 66 Images	10

In 67 Images	14
In 68 Images	10
In 69 Images	11
In 70 Images	5
In 71 Images	6
In 72 Images	4
In 73 Images	4
In 74 Images	5
In 75 Images	2
In 77 Images	6
In 78 Images	3
In 80 Images	1
In 81 Images	4
In 82 Images	3
In 84 Images	1
In 85 Images	1
In 86 Images	1
In 92 Images	1
In 98 Images	2
In 109 Images	1
In 114 Images	1

2D Keypoint Matches



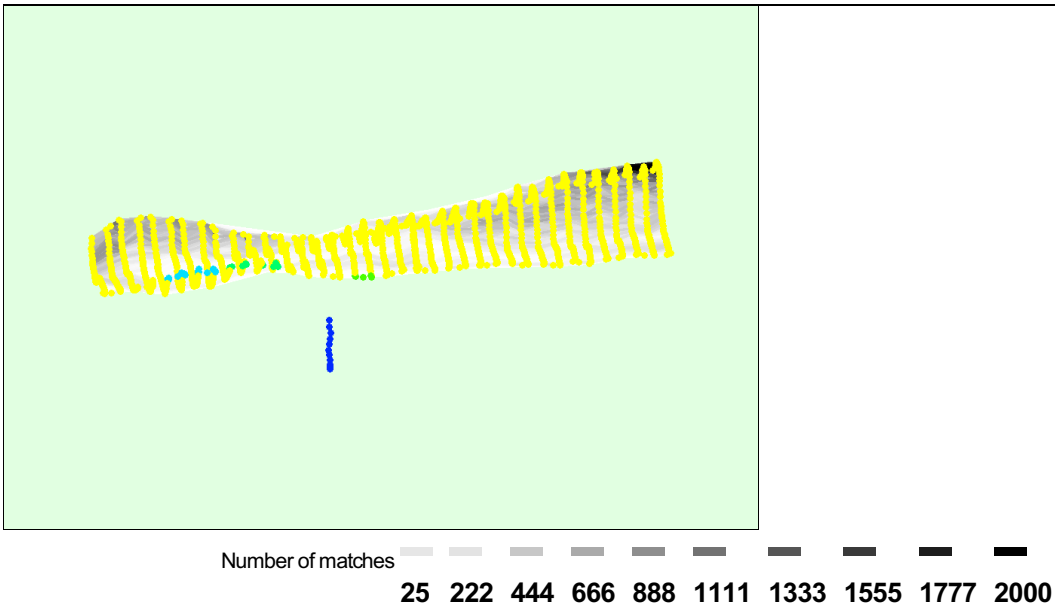


Figure 5: Computed image positions with links between matched images. The darkness of the links indicates the number of matched 2D keypoints between the images. Bright links indicate weak links and require manual tie points or more images.

Geolocation Details

Absolute Geolocation Variance

Min Error [m]	Max Error [m]	Geolocation Error X [%]	Geolocation Error Y [%]	Geolocation Error Z [%]
-	-15.00	0.00	0.00	0.00
-15.00	-12.00	0.00	0.00	0.00
-12.00	-9.00	0.00	0.00	0.00
-9.00	-6.00	0.00	0.26	0.00
-6.00	-3.00	0.00	13.61	0.10
-3.00	0.00	57.73	38.32	45.04
0.00	3.00	41.65	33.85	54.55
3.00	6.00	0.56	13.82	0.31
6.00	9.00	0.05	0.15	0.00
9.00	12.00	0.00	0.00	0.00
12.00	15.00	0.00	0.00	0.00
15.00	-	0.00	0.00	0.00
Mean [m]		-0.000001	-0.000001	-0.000002
Sigma [m]		0.547114	2.523099	1.112659
RMS Error [m]		0.547114	2.523099	1.112659

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]	99.95	97.07	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]	5.000000	5.000000	10.000000
Sigma of Geolocation Accuracy [m]	0.000000	0.000000	0.000000

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

Geolocation Orientational Variance	RMS [degree]
Omega	0.822
Phi	0.680
Kappa	5.773

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) i7-8700K CPU @ 3.70GHz RAM: 64GB GPU: NVIDIA GeForce GTX 1080 Ti (Driver: 24.21.13.9882), Intel(R) UHD Graphics 630 (Driver: 22.20.16.4758)
Operating System	Windows 10 Education, 64-bit

Coordinate Systems

Image Coordinate System	WGS84 (egm96)
Output Coordinate System	WGS 84 / UTM zone 10N (egm96)

Processing Options

Detected Template	RGB Local structure bark beetle severity*
Keypoints Image Scale	Custom, Image Scale: 0.5
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, no

Point Cloud Densification details

Processing Options

Image Scale	multiscale, 1/2 (Half image size, Default)
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	05h:35m:42s
Time for Point Cloud Classification	NA
Time for 3D Textured Mesh Generation	45m:10s

Results

Number of Generated Tiles	4
Number of 3D Densified Points	89391745
Average Density (per m^3)	33.6

DSM, Orthomosaic and Index Details

Processing Options

DSM and Orthomosaic Resolution	1 x GSD (4.64 [cm/pixel])
DSM Filters	Noise Filtering: yes Surface Smoothing: yes, Type: Sharp
Raster DSM	Generated: yes Method: Triangulation Merge Tiles: yes
Orthomosaic	Generated: yes Merge Tiles: yes GeoTIFF Without Transparency: no Google Maps Tiles and KML: no
Time for DSM Generation	14m:11s
Time for Orthomosaic Generation	15h:37m:22s
Time for DTM Generation	00s
Time for Contour Lines Generation	00s
Time for Reflectance Map Generation	00s
Time for Index Map Generation	00s