Quality Report

Generated with Pix4Dmapper version 4.6.4

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	4field-multispectral-20210604
Processed	2021-06-11 17:40:18
Camera Model Name(s)	FC6360_5.7_1600x1300 (Blue), FC6360_5.7_1600x1300 (Green), FC6360_5.7_1600x1300 (Red), FC6360_5.7_1600x1300 (Red edge), FC6360_5.7_1600x1300 (NIR), FC6360_5.7_1600x1300 (RGB)
Rig name(s)	«FC6360»
Average Ground Sampling Distance (GSD)	1.11 cm / 0.44 in
Area Covered	0.000 km^2 / 0.0000 ha / 0.00 sq. mi. / 0.0000 acres
Time for Initial Processing (without report)	27m:28s

Quality Check

Images	median of 10000 keypoints per image	✓
Dataset	1111 out of 1111 images calibrated (100%), 4 images disabled	✓
Camera Optimization	4.16% relative difference between initial and optimized internal camera parameters	✓
Matching	median of 6153.57 matches per calibrated image	✓
Georeferencing	yes, 5 GCPs (5 3D), mean RMS error = 0.007 m	✓

Preview

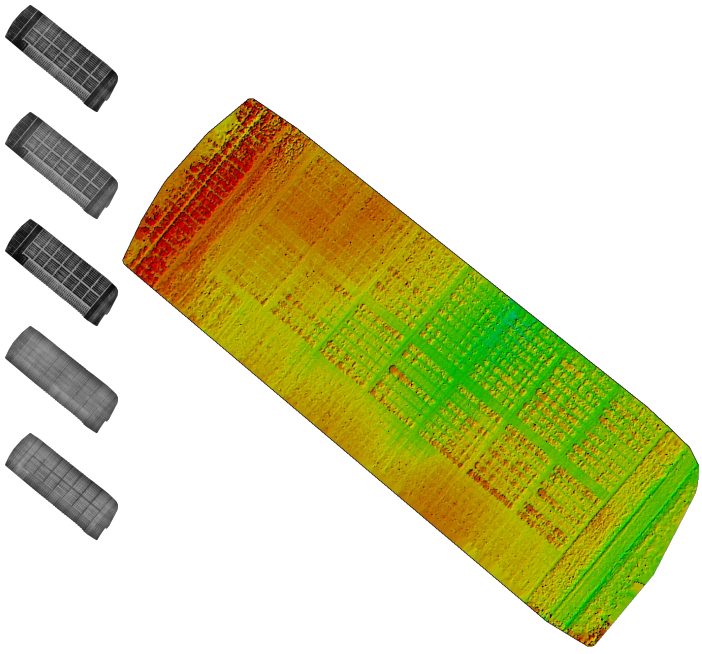


Figure 1: Orthomosaic and the corresponding sparse Digital Surface Model (DSM) before densification.

Calibration Details

Number of Calibrated Images	1111 out of 1115
Number of Geolocated Images	1115 out of 1115

Initial Image Positions

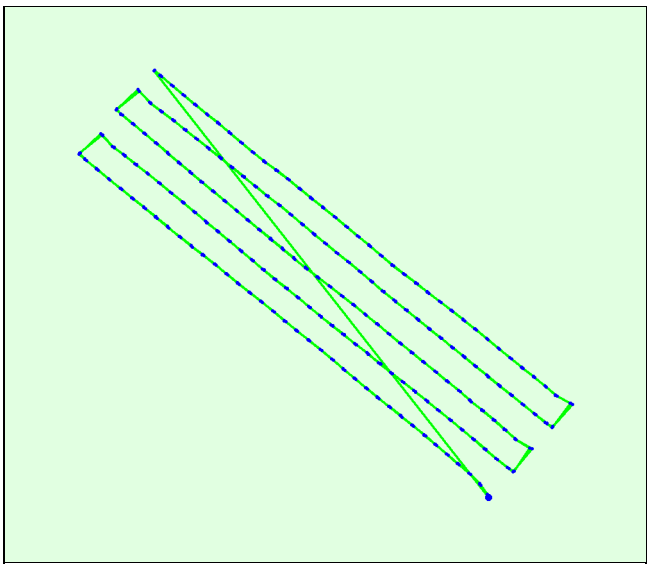
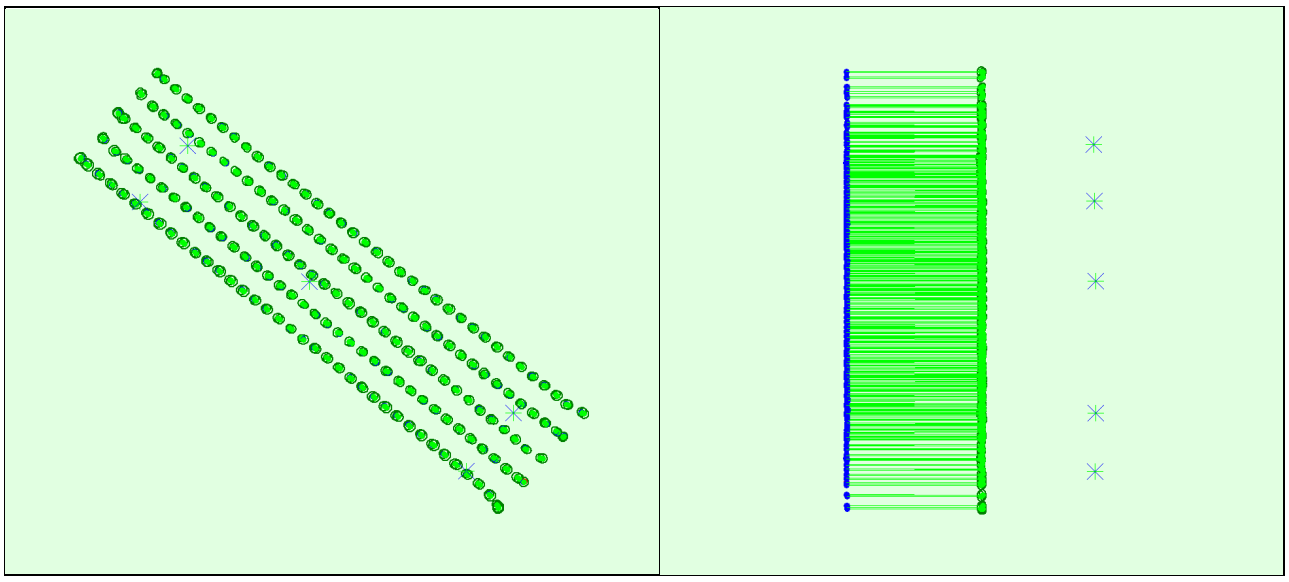
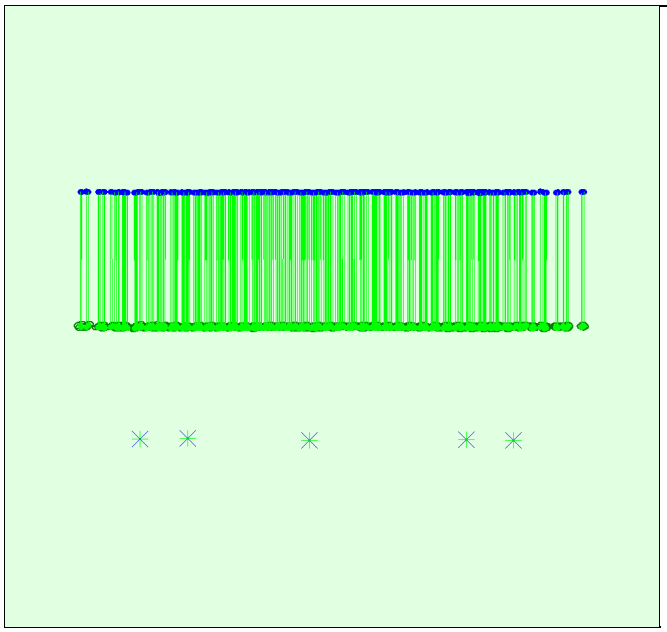


Figure 2: Top view of the initial image position. The green line follows the position of the images in time starting from the large blue dot.

Computed Image/GCPs/Manual Tie Points Positions





Uncertainty ellipses 100x 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	0.008	0.008	0.005	0.022	0.022	0.008
Sigma	0.001	0.001	0.000	0.003	0.003	0.001

Overlap

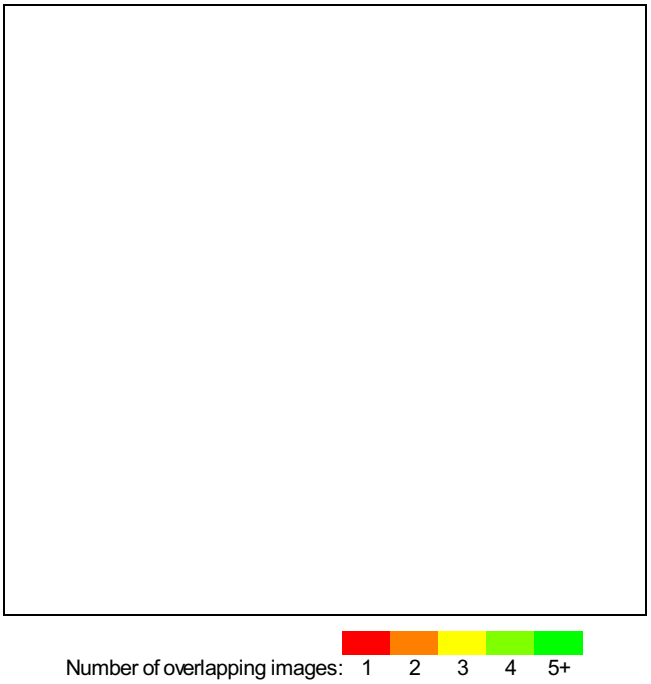


**Figure 4: Number of overlapping images computed for each pixel of the orthomosaic.
Red and yellow areas indicate low overlap for which poor results may be generated. Green areas indicate an overlap of over 5 images for every pixel. Good quality results will be generated as long as the number of keypoint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

Bundle Block Adjustment Details

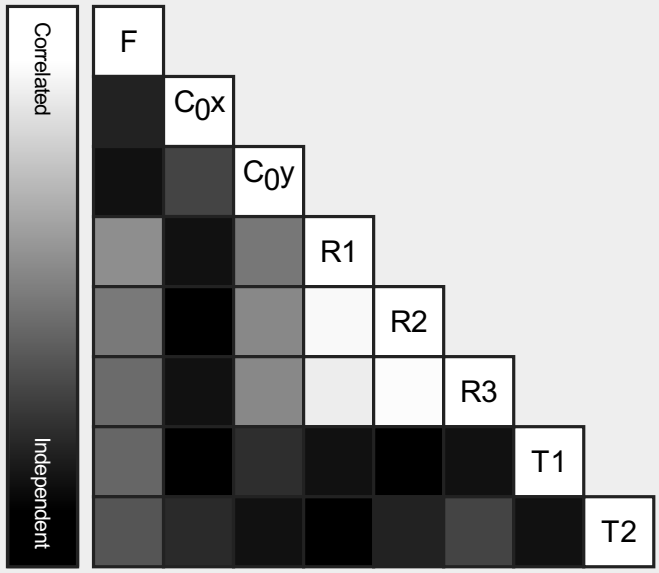
Number of 2D Keypoint Observations for Bundle Block Adjustment	2770015
Number of 3D Points for Bundle Block Adjustment	606410
Mean Reprojection Error [pixels]	0.236

Internal Camera Parameters

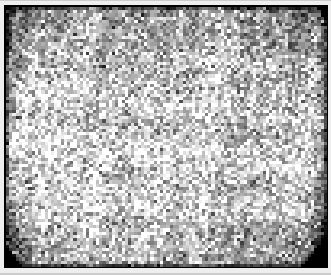
FC6360_5.7_1600x1300 (Blue). Sensor Dimensions: 5.022 [mm] x 4.081 [mm]

EXIF ID: FC6360_5.7_1600x1300

	Focal Length	Principal Point x	Principal Point y	R1	R2	R3	T1	T2
Initial Values	1828.571 [pixel] 5.740 [mm]	766.783 [pixel] 2.407 [mm]	594.700 [pixel] 1.867 [mm]	-0.407	0.330	-0.315	0.001	0.001
Optimized Values	1881.616 [pixel] 5.907 [mm]	776.347 [pixel] 2.437 [mm]	599.887 [pixel] 1.883 [mm]	-0.259	-0.479	1.119	0.002	0.001
Uncertainties (Sigma)	0.343 [pixel] 0.001 [mm]	0.460 [pixel] 0.001 [mm]	0.408 [pixel] 0.001 [mm]	0.003	0.020	0.040	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.



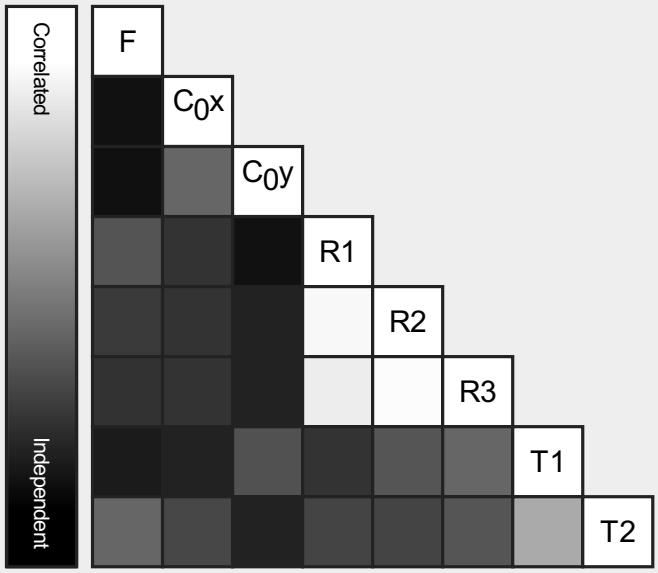
The number of Automatic Tie Points (ATPs) per pixel, averaged over all images of the camera model, is color coded between black and white. White indicates that, on average, more than 16 ATPs have been extracted at the pixel location. Black indicates that, on average, 0 ATPs have been extracted at the 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.

Internal Camera Parameters

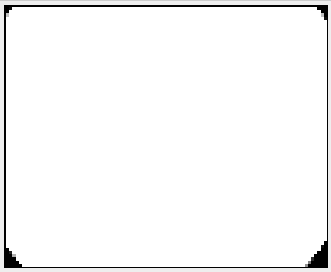
FC6360_5.7_1600x1300 (Green). Sensor Dimensions: 5.022 [mm] x 4.081 [mm]

EXIF ID: FC6360_5.7_1600x1300

	Focal Length	Principal Point x	Principal Point y	R1	R2	R3	T1	T2
Initial Values	1828.571 [pixel] 5.740 [mm]	766.472 [pixel] 2.406 [mm]	594.871 [pixel] 1.867 [mm]	-0.404	0.310	-0.259	0.001	0.001
Optimized Values	1887.131 [pixel] 5.924 [mm]	788.266 [pixel] 2.474 [mm]	615.887 [pixel] 1.933 [mm]	-0.368	0.184	-0.056	0.001	0.001
Uncertainties (Sigma)	0.295 [pixel] 0.001 [mm]	0.224 [pixel] 0.001 [mm]	0.192 [pixel] 0.001 [mm]	0.001	0.007	0.014	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.



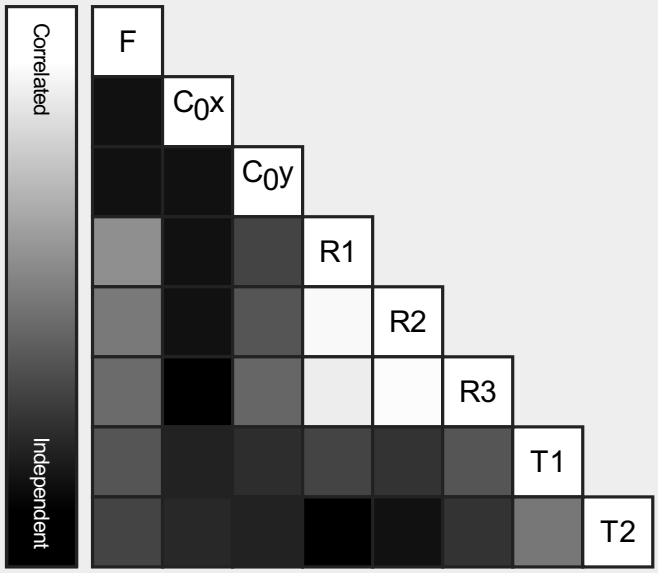
The number of Automatic Tie Points (ATPs) per pixel, averaged over all images of the camera model, is color coded between black and white. White indicates that, on average, more than 16 ATPs have been extracted at the pixel location. Black indicates that, on average, 0 ATPs have been extracted at the 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.

Internal Camera Parameters

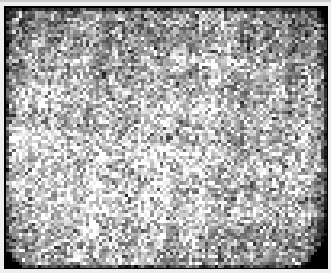
FC6360_5.7_1600x1300 (Red). Sensor Dimensions: 5.022 [mm] x 4.081 [mm]

EXIF ID: FC6360_5.7_1600x1300

	Focal Length	Principal Point x	Principal Point y	R1	R2	R3	T1	T2
Initial Values	1828.571 [pixel] 5.740 [mm]	766.944 [pixel] 2.407 [mm]	594.861 [pixel] 1.867 [mm]	-0.401	0.271	-0.135	0.001	0.001
Optimized Values	1877.301 [pixel] 5.893 [mm]	776.546 [pixel] 2.438 [mm]	610.402 [pixel] 1.916 [mm]	-0.268	-0.422	1.022	0.000	0.000
Uncertainties (Sigma)	0.342 [pixel] 0.001 [mm]	0.458 [pixel] 0.001 [mm]	0.409 [pixel] 0.001 [mm]	0.003	0.020	0.039	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.



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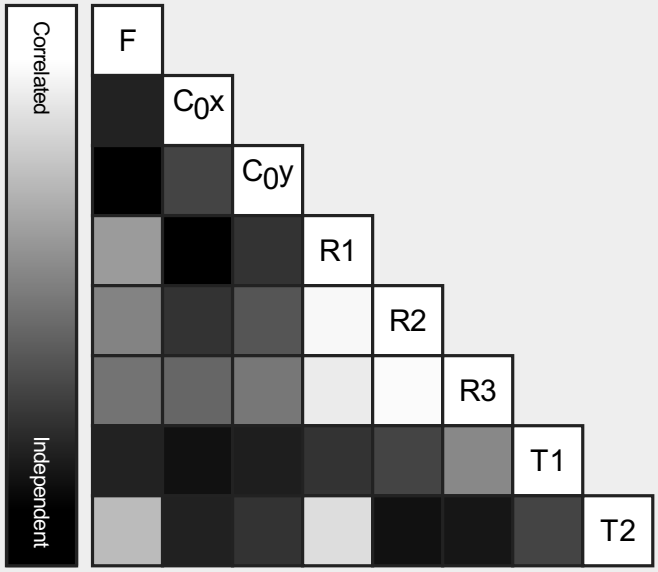
Internal Camera Parameters

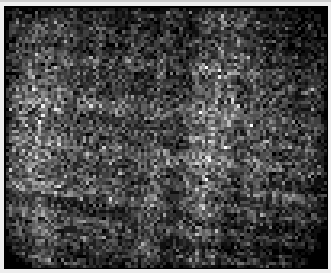
FC6360_5.7_1600x1300 (Red edge). Sensor Dimensions: 5.022 [mm] x 4.081 [mm]

EXIF ID: FC6360_5.7_1600x1300

	Focal Length	Principal Point x	Principal Point y	R1	R2	R3	T1	T2
Initial Values	1828.571 [pixel] 5.740 [mm]	766.538 [pixel] 2.406 [mm]	595.453 [pixel] 1.869 [mm]	-0.400	0.270	-0.132	0.001	0.001
Optimized Values	1874.892 [pixel] 5.885 [mm]	773.510 [pixel] 2.428 [mm]	612.277 [pixel] 1.922 [mm]	-0.206	-0.808	1.753	0.000	0.000
Uncertainties (Sigma)	0.364 [pixel] 0.001 [mm]	0.510 [pixel] 0.002 [mm]	0.466 [pixel] 0.001 [mm]	0.004	0.026	0.053	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.



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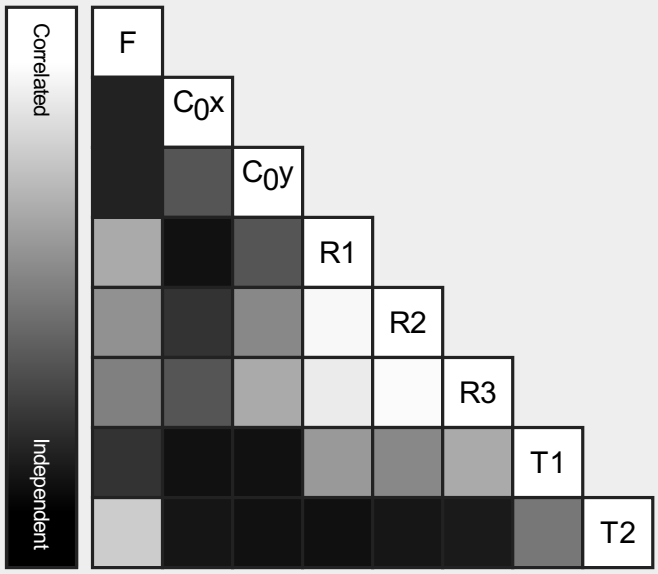
Internal Camera Parameters

FC6360_5.7_1600x1300 (NIR). Sensor Dimensions: 5.022 [mm] x 4.081 [mm]

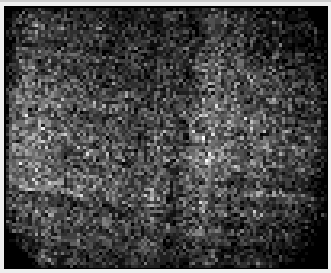
EXIF ID: FC6360_5.7_1600x1300

	Focal Length	Principal Point x	Principal Point y	R1	R2	R3	T1	T2
Initial Values	1828.571 [pixel] 5.740 [mm]	766.438 [pixel] 2.406 [mm]	595.269 [pixel] 1.869 [mm]	-0.400	0.269	-0.134	0.001	0.001
Optimized Values	1871.150 [pixel] 5.874 [mm]	773.784 [pixel] 2.429 [mm]	604.430 [pixel] 1.897 [mm]	-0.120	-1.417	3.032	0.001	0.001

Uncertainties (Sigma)	0.399 [pixel] 0.001 [mm]	0.526 [pixel] 0.002 [mm]	0.500 [pixel] 0.002 [mm]	0.005	0.035	0.076	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.



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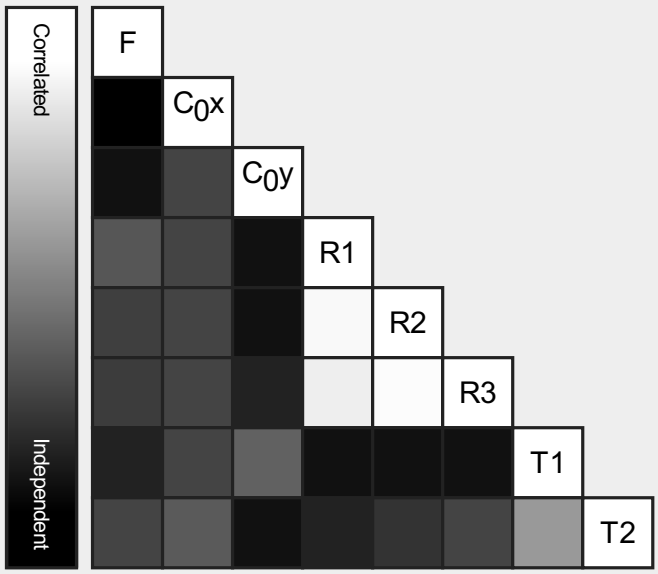
Internal Camera Parameters

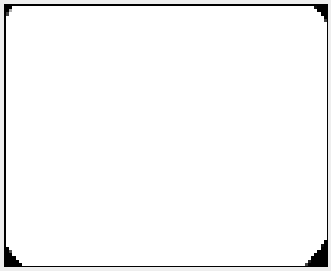
FC6360_5.7_1600x1300 (RGB). Sensor Dimensions: 5.022 [mm] x 4.081 [mm]

EXIF ID: FC6360_5.7_1600x1300

	Focal Length	Principal Point x	Principal Point y	R1	R2	R3	T1	T2
Initial Values	2173.920 [pixel] 6.824 [mm]	780.964 [pixel] 2.451 [mm]	639.519 [pixel] 2.007 [mm]	-0.511	0.507	-0.546	0.000	0.000
Optimized Values	1926.728 [pixel] 6.048 [mm]	787.231 [pixel] 2.471 [mm]	623.023 [pixel] 1.956 [mm]	-0.471	0.748	-1.065	0.000	0.000
Uncertainties (Sigma)	0.339 [pixel] 0.001 [mm]	0.238 [pixel] 0.001 [mm]	0.208 [pixel] 0.001 [mm]	0.001	0.008	0.016	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.



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Camera Rig «FC6360» Relatives. Images: 925

	Transl X [m]	Transl Y [m]	Transl Z [m]	Rot X [degree]	Rot Y [degree]	Rot Z [degree]
FC6360_5.7_1600x1300 (Green)	Reference Camera					
FC6360_5.7_1600x1300 (Blue)						
Initial Values	0.000	0.016	0.000	0.000	0.000	0.000
Optimized values	0.000	0.016	0.000	0.303	-0.431	0.027
Uncertainties (sigma)				0.014	0.016	0.002
FC6360_5.7_1600x1300 (Red)						
Initial Values	0.016	0.016	0.000	0.000	0.000	0.000
Optimized values	0.016	0.016	0.000	0.365	-0.337	0.010
Uncertainties (sigma)				0.014	0.016	0.002
FC6360_5.7_1600x1300 (Red edge)						
Initial Values	0.032	0.000	0.000	0.000	0.000	0.000
Optimized values	0.032	0.000	0.000	0.711	-0.596	0.019
Uncertainties (sigma)				0.015	0.017	0.002
FC6360_5.7_1600x1300 (NIR)						
Initial Values	0.016	0.000	0.000	0.000	0.000	0.000
Optimized values	0.016	0.000	0.000	0.701	-0.715	0.013
Uncertainties (sigma)				0.016	0.018	0.002

2D Keypoints Table

	Number of 2D Keypoints per Image	Number of Matched 2D Keypoints per Image
Median	10000	6154
Min	9516	386
Max	10000	7622
Mean	9985	6088

2D Keypoints Table for Camera FC6360_5.7_1600x1300 (Blue)

	Number of 2D Keypoints per Image	Number of Matched 2D Keypoints per Image
Median	10000	5685
Min	9978	3248
Max	10000	6818
Mean	9998	5657

2D Keypoints Table for Camera FC6360_5.7_1600x1300 (Green)

	Number of 2D Keypoints per Image	Number of Matched 2D Keypoints per Image
Median	10000	6290
Min	9518	4693
Max	10000	7622
Mean	9983	6312

2D Keypoints Table for Camera FC6360_5.7_1600x1300 (Red)

	Number of 2D Keypoints per Image	Number of Matched 2D Keypoints per Image

Median	10000	5731
Min	10000	4202
Max	10000	6569
Mean	10000	5738

2D Keypoints Table for Camera FC6360_5.7_1600x1300 (Red edge)

	Number of 2D Keypoints per Image	Number of Matched 2D Keypoints per Image
Median	10000	4690
Min	9944	1104
Max	10000	6995
Mean	9997	4780

2D Keypoints Table for Camera FC6360_5.7_1600x1300 (NIR)

	Number of 2D Keypoints per Image	Number of Matched 2D Keypoints per Image
Median	10000	4845
Min	10000	386
Max	10000	7364
Mean	10000	4859

2D Keypoints Table for Camera FC6360_5.7_1600x1300 (RGB)

	Number of 2D Keypoints per Image	Number of Matched 2D Keypoints per Image
Median	10000	6212
Min	9516	4635
Max	10000	7407
Mean	9982	6240

Median / 75%/ Maximal Number of Matches Between Camera Models

	FC6360_5.7_160... (Blue)	FC6360_5.7_16... (Green)	FC6360_5.7_1600... (Red)	FC6360_5.7... (Red edge)	FC6360_5.7_1600... (NIR)	FC6360_5.7_1600... (RGB)
FC6360_5.7_1600x1300 (Blue)	608 / 1751 / 4315	418 / 933 / 4272	695 / 1754 / 4115	202 / 387 / 868	134 / 278 / 651	345 / 745 / 2616
FC6360_5.7_1600x1300 (Green)		488 / 1086 / 5987	398 / 866 / 3929	118 / 275 / 1089	78 / 183 / 799	404 / 863 / 4048
FC6360_5.7_1600x1300 (Red)			525 / 2055 / 4667	198 / 437 / 1032	139 / 331 / 778	324 / 717 / 2889
FC6360_5.7_1600x1300 (Red edge)				212 / 1606 / 5380	174 / 350 / 1049	88 / 193 / 586
FC6360_5.7_1600x1300 (NIR)					159 / 2169 / 5764	57 / 140 / 496
FC6360_5.7_1600x1300 (RGB)						460 / 988 / 5024

3D Points from 2D Keypoint Matches

	Number of 3D Points Observed
In 2 Images	313964
In 3 Images	102031
In 4 Images	48995
In 5 Images	29671
In 6 Images	19293
In 7 Images	13339
In 8 Images	10495
In 9 Images	8313
In 10 Images	7342
In 11 Images	5787
In 12 Images	4829
In 13 Images	3964

In 14 Images	3597
In 15 Images	3155
In 16 Images	2943
In 17 Images	2516
In 18 Images	2278
In 19 Images	2268
In 20 Images	2276
In 21 Images	1913
In 22 Images	1790
In 23 Images	1526
In 24 Images	1413
In 25 Images	1272
In 26 Images	1217
In 27 Images	1031
In 28 Images	1008
In 29 Images	865
In 30 Images	860
In 31 Images	826
In 32 Images	670
In 33 Images	636
In 34 Images	516
In 35 Images	494
In 36 Images	474
In 37 Images	385
In 38 Images	328
In 39 Images	329
In 40 Images	259
In 41 Images	245
In 42 Images	183
In 43 Images	172
In 44 Images	160
In 45 Images	109
In 46 Images	103
In 47 Images	77
In 48 Images	76
In 49 Images	64
In 50 Images	62
In 51 Images	49
In 52 Images	44
In 53 Images	39
In 54 Images	34
In 55 Images	28
In 56 Images	16
In 57 Images	20
In 58 Images	23
In 59 Images	8
In 60 Images	11
In 61 Images	5
In 62 Images	4
In 63 Images	2
In 64 Images	2
In 65 Images	2
In 67 Images	2
In 68 Images	2

2D Keypoint Matches

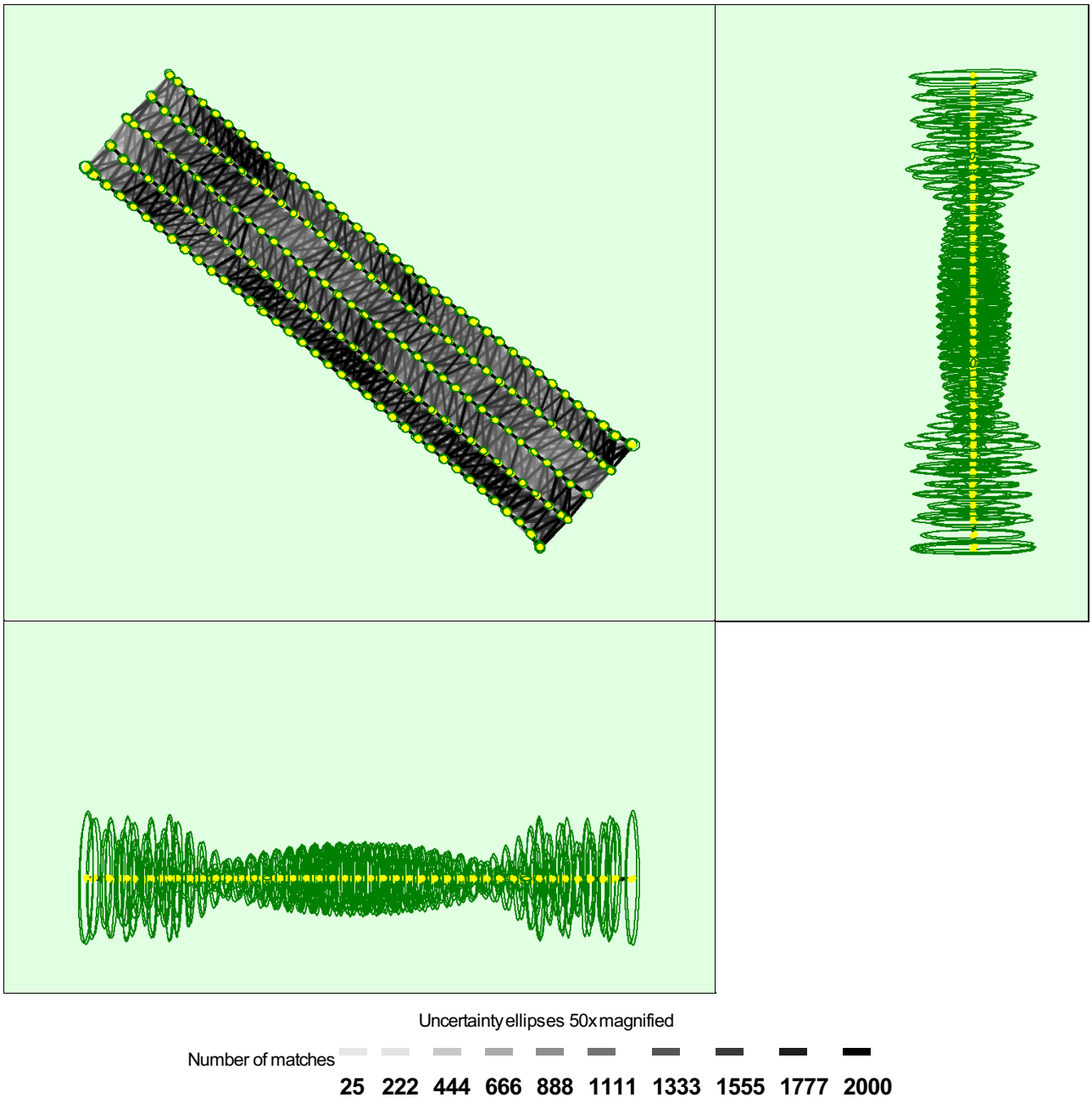

Figure 5: Computed image positions with links between matched images. The darkness of the links indicates the number of matched 2D keypoints between the images. Bright links indicate weak links and require manual tie points or more images. Dark green ellipses indicate the relative camera position uncertainty 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	0.013	0.012	0.089	0.197	0.357	0.016
Sigma	0.002	0.002	0.053	0.125	0.206	0.006

Geolocation Details

Ground Control Points

GCP Name	Accuracy XY/Z [m]	Error X [m]	Error Y [m]	Error Z [m]	Projection Error [pixel]	Verified/Marked
GCP16 (3D)	0.020/ 0.020	-0.015	-0.004	0.001	0.549	8 / 8
GCP17 (3D)	0.020/ 0.020	-0.003	-0.011	0.006	0.498	11 / 11

GCP18 (3D)	0.020/ 0.020	-0.002	0.001	-0.010	0.664	9 / 9
GCP19 (3D)	0.020/ 0.020	0.003	0.004	0.001	0.744	9 / 9
GCP20 (3D)	0.020/ 0.020	0.017	0.010	-0.001	0.873	11 / 11
Mean [m]		0.000007	0.000045	-0.000597		
Sigma [m]		0.010197	0.007180	0.005394		
RMS Error [m]		0.010197	0.007181	0.005427		

Localisation accuracy per GCP and mean errors in the three coordinate directions. The last column counts the number of calibrated images where the GCP has been automatically verified vs. manually marked.

Absolute Geolocation Variance

Min Error [m]	Max Error [m]	Geolocation Error X [%]	Geolocation Error Y [%]	Geolocation Error Z [%]
-	-0.07	0.18	0.09	16.74
-0.07	-0.06	1.08	0.18	0.00
-0.06	-0.04	7.29	1.80	0.00
-0.04	-0.03	9.90	6.30	0.00
-0.03	-0.01	13.59	8.37	0.00
-0.01	0.00	19.44	27.90	0.00
0.00	0.01	25.38	31.59	0.00
0.01	0.03	13.41	12.33	0.00
0.03	0.04	6.57	9.63	0.00
0.04	0.06	2.70	1.71	0.00
0.06	0.07	0.36	0.00	0.00
0.07	-	0.09	0.09	83.26
Mean [m]		-0.003947	-0.000222	24.079795
Sigma [m]		0.025834	0.020921	0.118581
RMS Error [m]		0.026134	0.020922	24.080087

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.

Geolocation Bias	X	Y	Z
Translation [m]	-0.000061	-0.002390	23.977721

Bias between image initial and computed geolocation given in output coordinate system.

Relative Geolocation Variance

Relative Geolocation Error	Images X [%]	Images Y [%]	Images Z [%]
[-1.00, 1.00]	52.30	64.45	0.00
[-2.00, 2.00]	80.74	86.77	0.00
[-3.00, 3.00]	96.67	99.28	0.36
Mean of Geolocation Accuracy [m]	0.017732	0.017732	0.037783
Sigma of Geolocation Accuracy [m]	0.000854	0.000854	0.003679

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

Geolocation Orientational Variance	RMS [degree]
Omega	1.193
Phi	1.076
Kappa	6.684

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) i5-3470 CPU @ 3.20GHz RAM: 16GB GPU: Intel(R) HD Graphics (Driver: 10.18.10.4252)
Operating System	Windows 10 Pro, 64-bit

Coordinate Systems

Image Coordinate System	WGS 84
Ground Control Point (GCP) Coordinate System	WGS 84
Output Coordinate System	WGS 84 / UTM zone 34N

Processing Options

Detected Template	No Template Available
Keypoints Image Scale	Full, Image Scale: 1
Advanced: Matching Image Pairs	Aerial Grid or Corridor
Advanced: Matching Strategy	Use Geometrically Verified Matching: yes
Advanced: Keypoint Extraction	Targeted Number of Keypoints: Custom, Number of Keypoints: 10000
Advanced: Calibration	Calibration Method: Alternative Internal Parameters Optimization: All prior External Parameters Optimization: All Rematch: Custom, yes
Rig «FC6360» processing	optimize relative rotation using a subset of secondary cameras

Point Cloud Densification details

Processing Options

Image Scale	multiscale, 1/2 (Half image size, Default)
Point Density	Low (Fast)
Minimum Number of Matches	3
3D Textured Mesh Generation	no
LOD	Generated: no
Advanced: Image Groups	Blue, Green, Red, Red edge, NIR, group1
Advanced: Use Processing Area	yes
Advanced: Use Annotations	yes
Time for Point Cloud Densification	04m:16s
Time for Point Cloud Classification	NA
Time for 3D Textured Mesh Generation	NA

Results

Number of Processed Clusters	2
Number of Generated Tiles	2
Number of 3D Densified Points	1396474
Average Density (per m^3)	746.02

DSM, Orthomosaic and Index Details

Processing Options

DSM and Orthomosaic Resolution	1 x GSD (1.11 [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
Radiometric calibration with reflectance target	yes
Index Calculator: Reflectance Map	Generated: yes Resolution: 1 x GSD (1.11 [cm/pixel]) Merge Tiles: yes
Index Calculator: Indices	AA-ndvi
Index Calculator: Index Values	Polygon Shapefile [cm/grid]: 400
Time for DSM Generation	03m:05s
Time for Orthomosaic Generation	31m:00s
Time for DTM Generation	00s
Time for Contour Lines Generation	00s
Time for Reflectance Map Generation	52m:34s
Time for Index Map Generation	01m:35s

Camera Radiometric Correction

Camera Name	Band	Radiometric Correction Type	Reflectance target
FC6360_5.7_1600x1300	Blue	Camera and Sun Irradiance	✓
FC6360_5.7_1600x1300	Green	Camera and Sun Irradiance	✓
FC6360_5.7_1600x1300	Red	Camera and Sun Irradiance	✓
FC6360_5.7_1600x1300	Red edge	Camera and Sun Irradiance	✓
FC6360_5.7_1600x1300	NIR	Camera and Sun Irradiance	✓
FC6360_5.7_1600x1300	Red Green Blue	No Correction	n/a