

AERIAL REMOTE SENSING & DIGITAL PHOTOGRAMMETRY

UNIT 8-9



Figure 1. 1:3000 Aerial Photograph (Reduced to 85%)

Dr. J. SARAVALAVEL

Assistant Professor

Department of Remote Sensing

Bharathidasan University

Email: saravanavel@bdu.ac.in

Data Capturing

Digital photogrammetry utilizes digital imagery as an input.

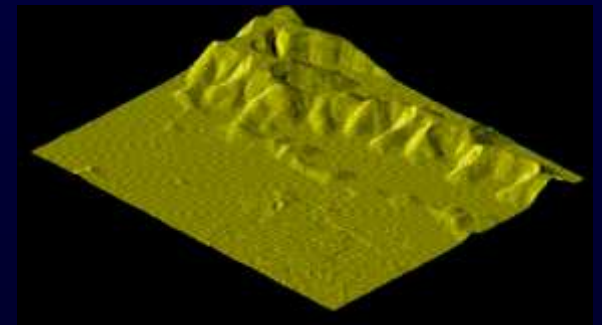
The rapid technological advances in computer hardware and software has motivated the shift from analog to digital imagery.

How can we get digital images?

- ❖ Scanning analog images.
- ❖ Using digital camera.

DIGITAL PHOTOGRAMMETRY

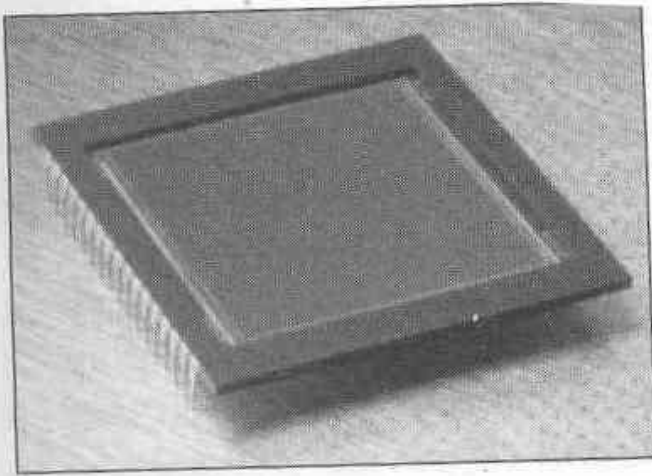
- Single or pairs of digital images are loaded into a computer with image processing capabilities.
- Images may be from satellite or airborne scanners, CCD cameras or are conventional photographs captured by a line scanner.
- Images are either displayed on the screen for operator interpretation, enhanced by image processing or subjected to image correlation in order to form a digital elevation model (DEM) or extract details.



Digital Frame Cameras

- ❑ A digital frame camera has similar geometric characteristic to a single-lens frame camera which employs film as its recording medium.
- ❑ Instead of film, the digital camera consists of a two-dimensional array of CCD elements (charge-coupled device) is called full frame sensor
- ❑ CCD is the type of solid-state detector in current. There are number of variations of CCD configurations, the basic operating principle is the same.

- ❖ At specific pixel location, the CCD elements is exposed to incident light energy and it builds up an electric charge proportional to the intensity of the incident light.
- ❖ The electric charge is subsequently amplified and converted from analog to digital form. A large number of CCDs can be combined on a silicon chip in a one-dimensional or two-dimensional array.
- ❖ Full frame sensor is mounted in the focal plane of a single-lens camera.
- ❖ Acquisition of an image exposes all CCD elements simultaneously, thus producing the digital image.



Full-frame sensor consists of an array of 4096 rows by 4096 columns of CCD elements and thus produces an image having nearly 16,800,000 pixels.

FIGURE 3-19

Kodak Digital Science KAF-16800 Image Sensor.
(Courtesy © Eastman Kodak Company.)

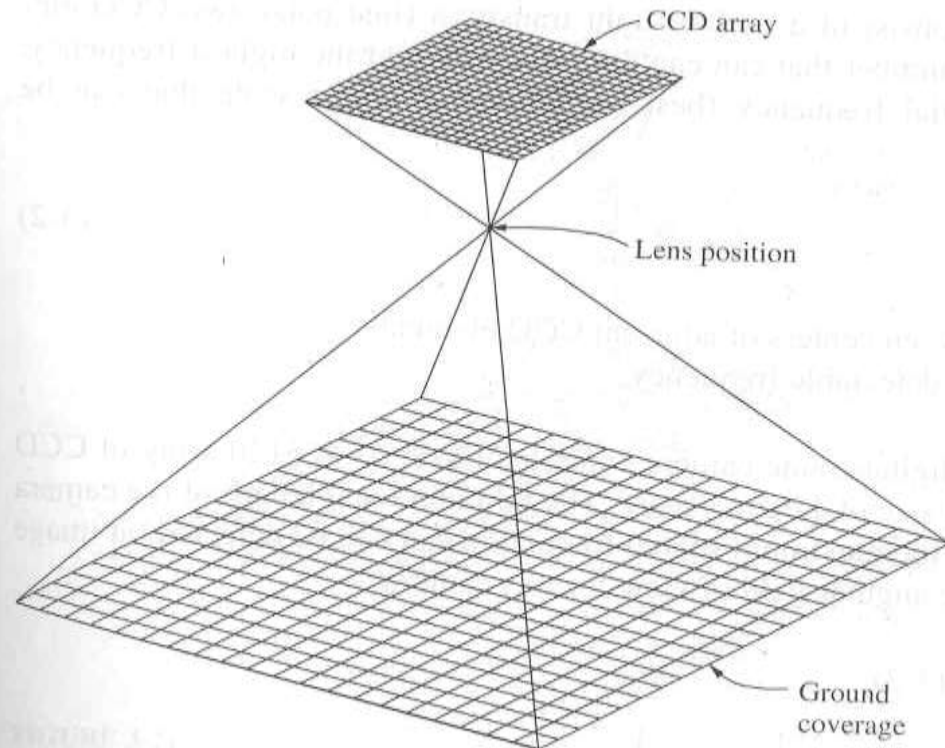
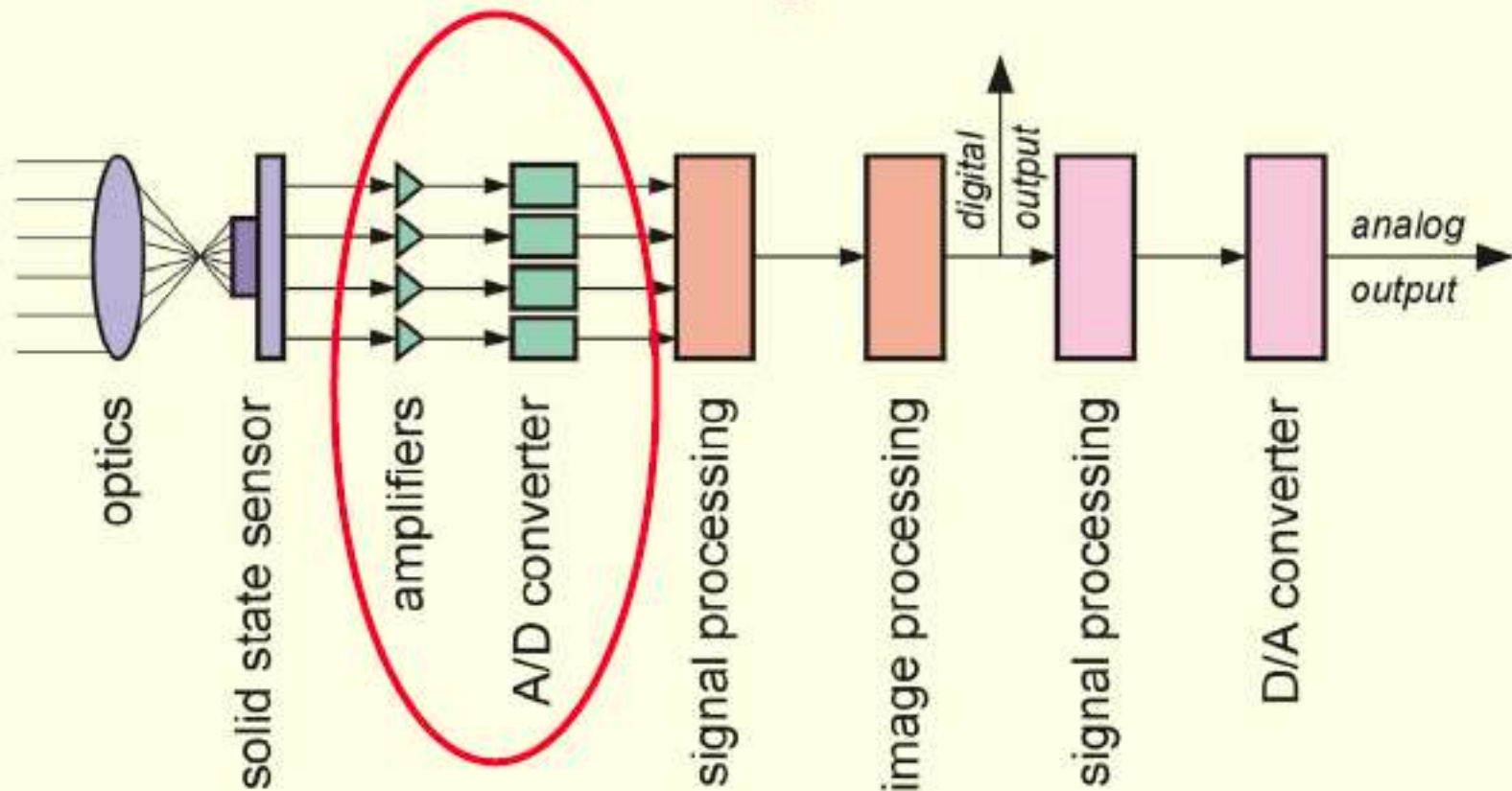


FIGURE 3-20

Geometry of a digital frame camera.

Digital Cameras: Block Diagram

Controls the dynamic range

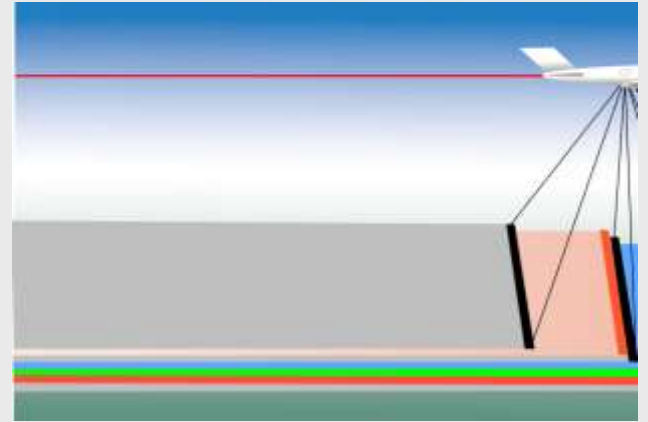
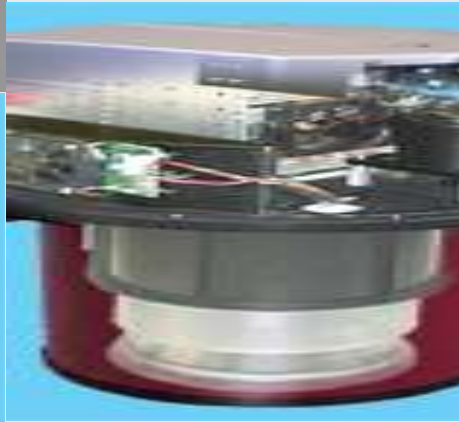


Analog Versus Digital Cameras

Components	Analog Cameras	Digital Camera
Optics	Lenses and Mirrors	Lenses and Mirrors
Detectors	Film	Solid State Detectors (CCD , CMOS)
Processors	Chemistry	Digital Computers
Output Media	Film	Computer Readable Disks and/or Tapes and Monitors

Camera Concepts

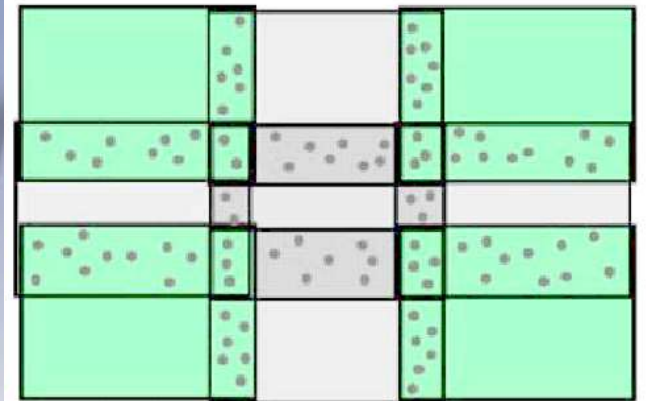
ADS40



Single lens sensor with 10 channels generates endless pixel carpets

DMS

UltraCam



Multi lens sensors with up to eight lenses generates patchwork frames

High Resolution Digital Aerial Cameras

Three-line Pushbroom Scanner

- ◆ Two solutions for development of digital aerial camera now available
 - **Three linear arrays** look forward, vertically and backwards to form three separate images as the aircraft moves over the terrain surface.
 - ◆ Images not perspective projections
 - ◆ System must include GPS/INS
 - **Images from smaller area arrays** are stitched together to form a larger frame image, which will have similar dimensions to a frame aerial film camera
 - ◆ Images will be perspective projections
 - ◆ No GPS/INS system required

Push-broom sensors

- ◆ The geometry of the complete image is not a perspective projection. Hence, special software is required.
- ◆ GPS/IMU system is essential to determine the camera exterior orientation (positions and attitude) during flight – extra cost
- ◆ Linear arrays are less subject to loss of pixels
- ◆ If bad pixels do occur, fewer pixels available to interpolate lost data
- ◆ Linear arrays are claimed to have larger dynamic range
- ◆ Linear arrays in principle are more suited to smaller scale imaging because of motion of the aircraft.
- ◆ Linear array systems have recently demonstrated GSD of 5cm
- ◆ Most linear array systems enable the acquisition of only 3 images per point along-track, but multiple imaging is possible across-track

	Leica Geosystems ADS40	Wehrli 3-DAS-1
Focal length	62.5 mm	110mm (or 80mm)
Pixel size (pitch)	6.5 μm	9 μm
Panchromatic line	2 * 12000 pixel (staggered)	3 * 8023 pixels
RGB and NIR line	12000 pixels	n/a
FoV (across track)	46°	36°
Stereo angle forward to nadir	26°	26°
Stereo angle forward to backward	42° - B/H=0.77	42° - B/H=0.77
Stereo angle nadir to backward	16°	16°
Dynamic range	12-bit	14-bits
Ground sample distance	16 cm at 3000 m altitude	18cm at 2200m
Swath width (3000 m Altitude)	3.75 km	3.75km at 2200m

Digital Camera Concepts



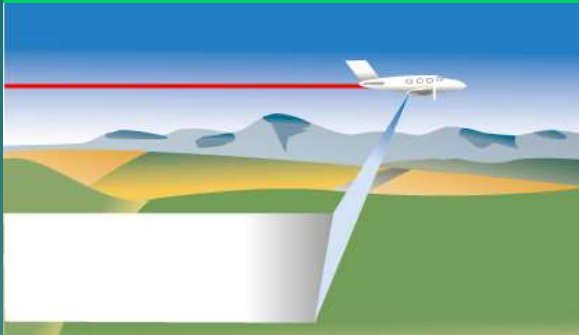
digital frames



pixel carpets

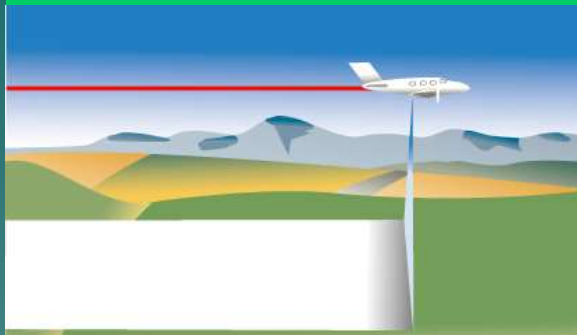
Three-line Pushbroom Scanner

Backward scene



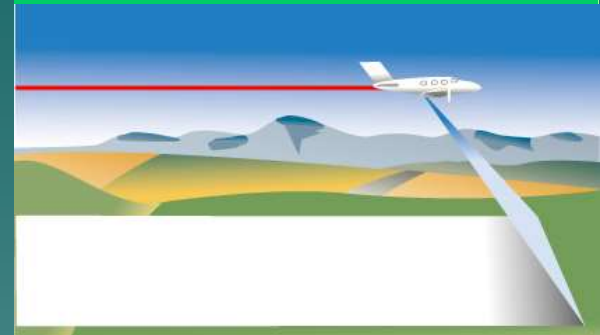
**composed
of backward view lines**

Nadir scene



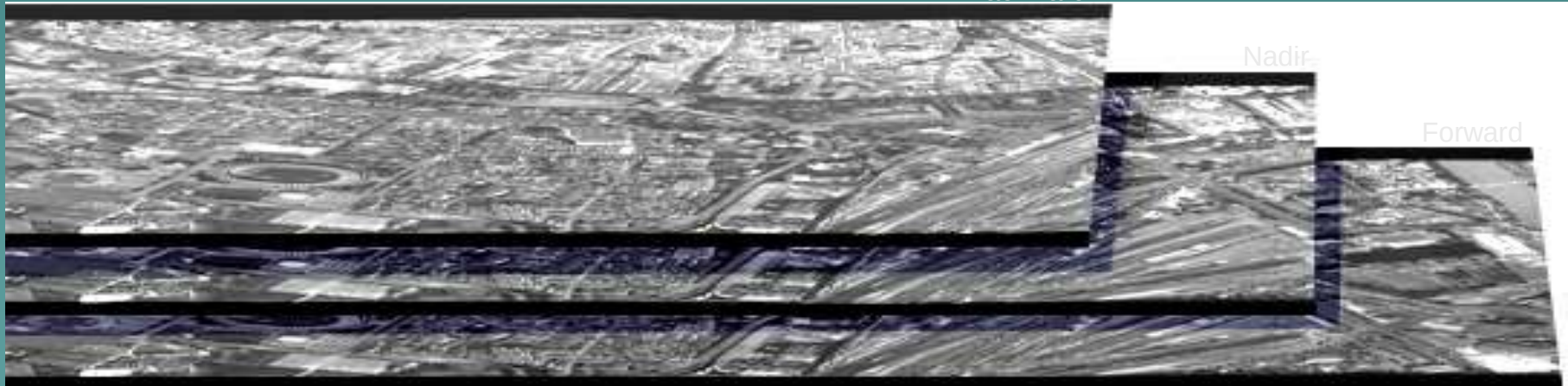
**composed
of nadir view lines**

Forward scene



**composed
of forward view lines**

Backward





DATA ACQUISITION BY LEICA GEOSYSTEMS ADS40

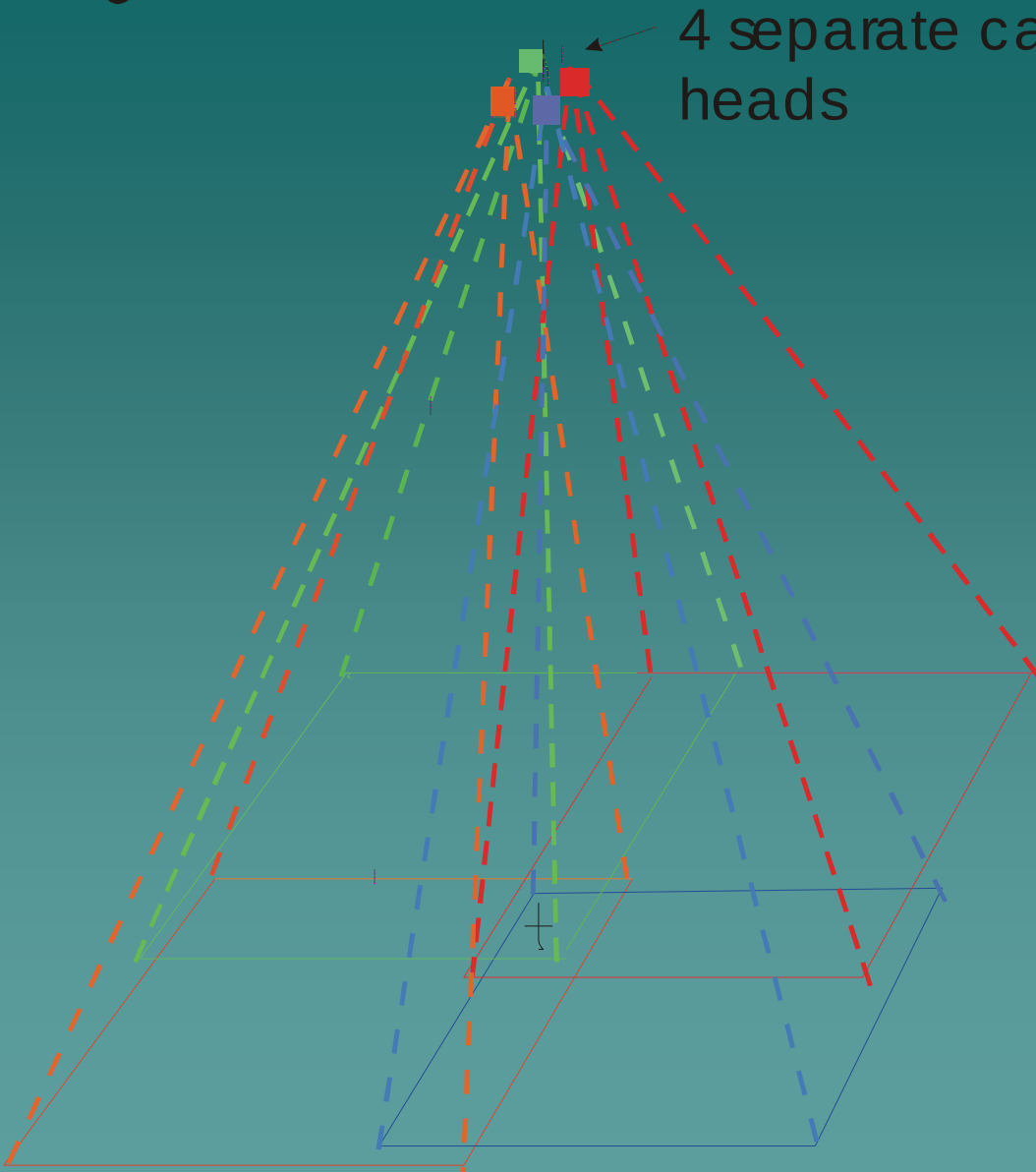
ADS40 unrectified



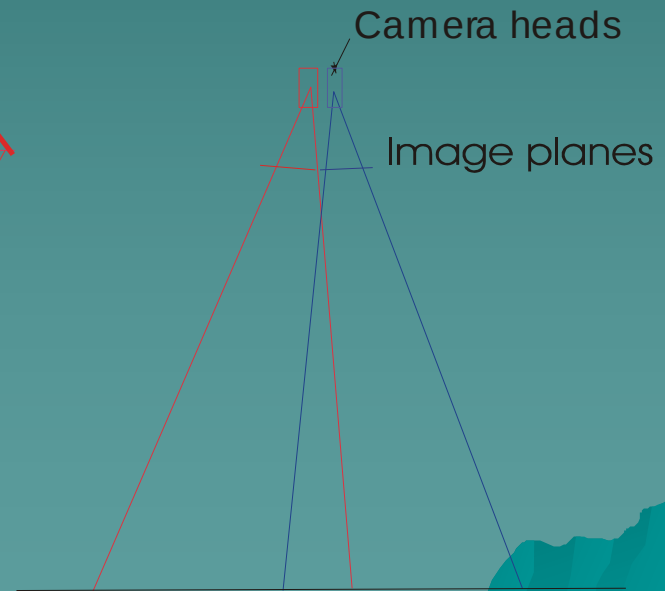
ADS40 rectified



Schematic diagram of DMC panchromatic digital camera



4 separate camera heads

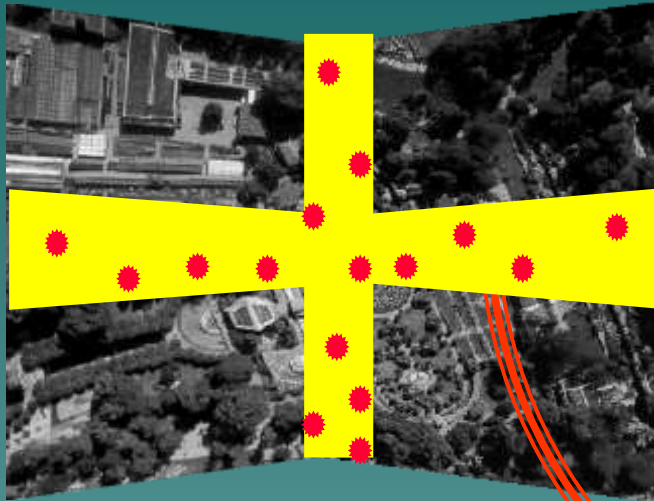


2D view of two camera heads

Areas covered by each camera

Image Processing

4 overlapping images



 tie point
area

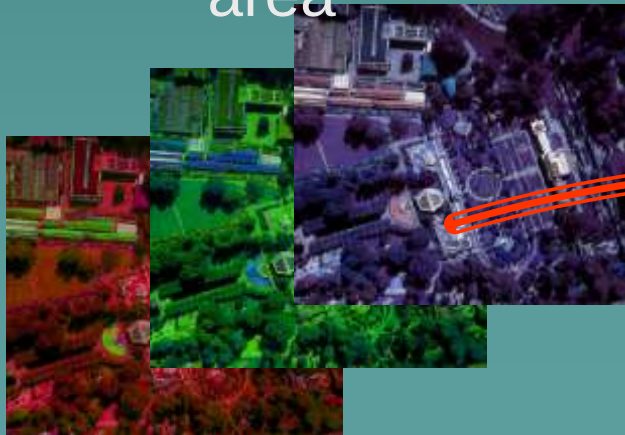
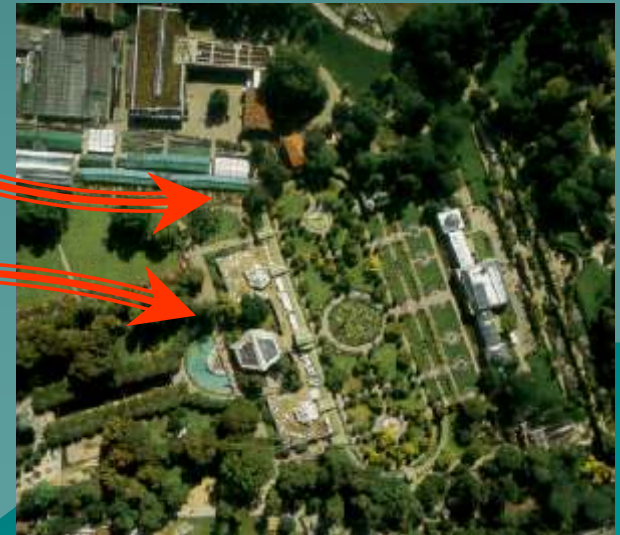
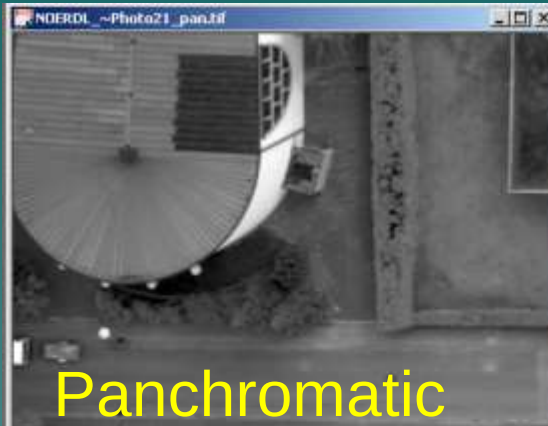


image mosaicing

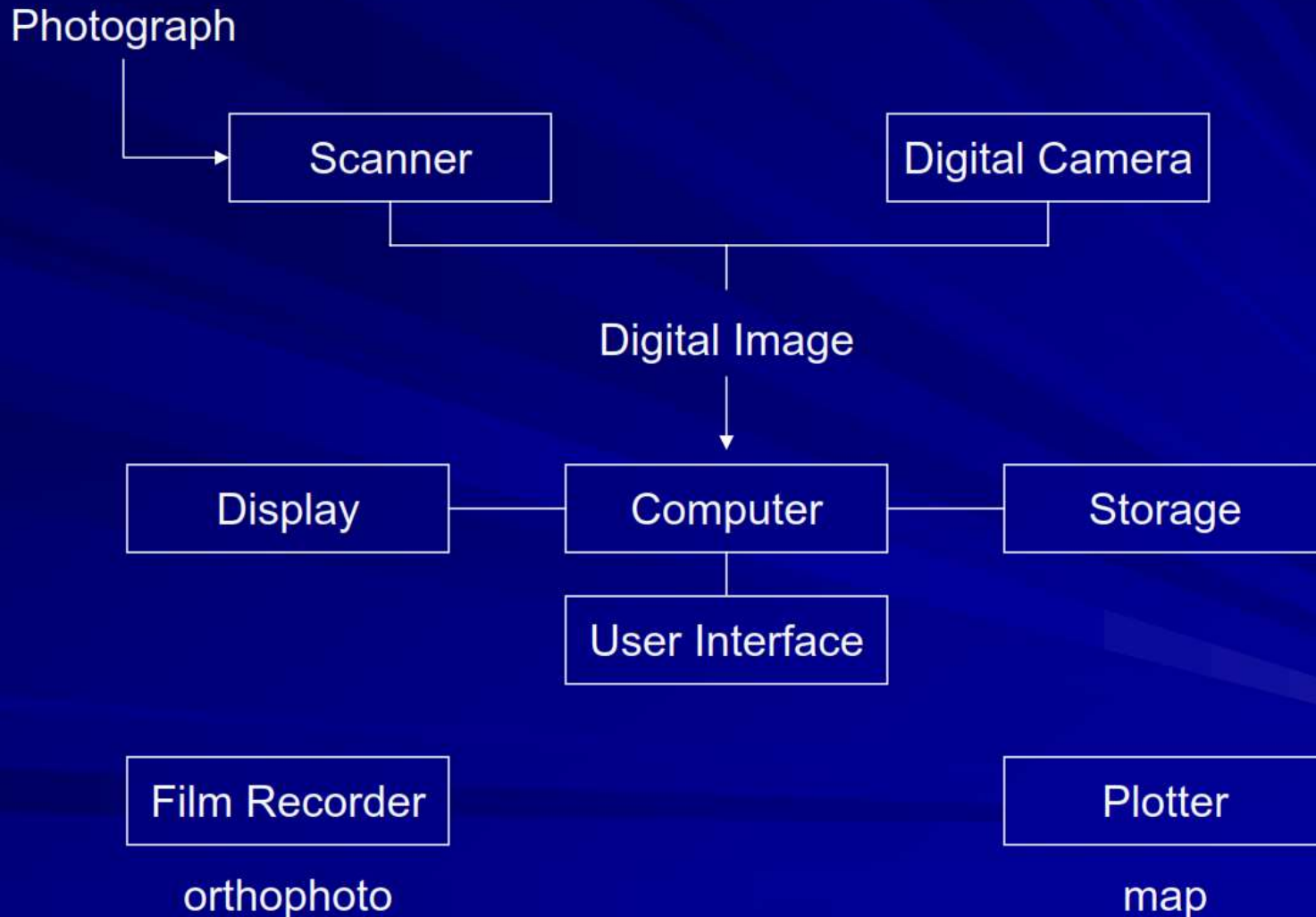
- apply camera calibration parameters
- apply platform calibration
- tie point check
- robust adjustment
- projection to virtual perspective
- fusion with colour composite



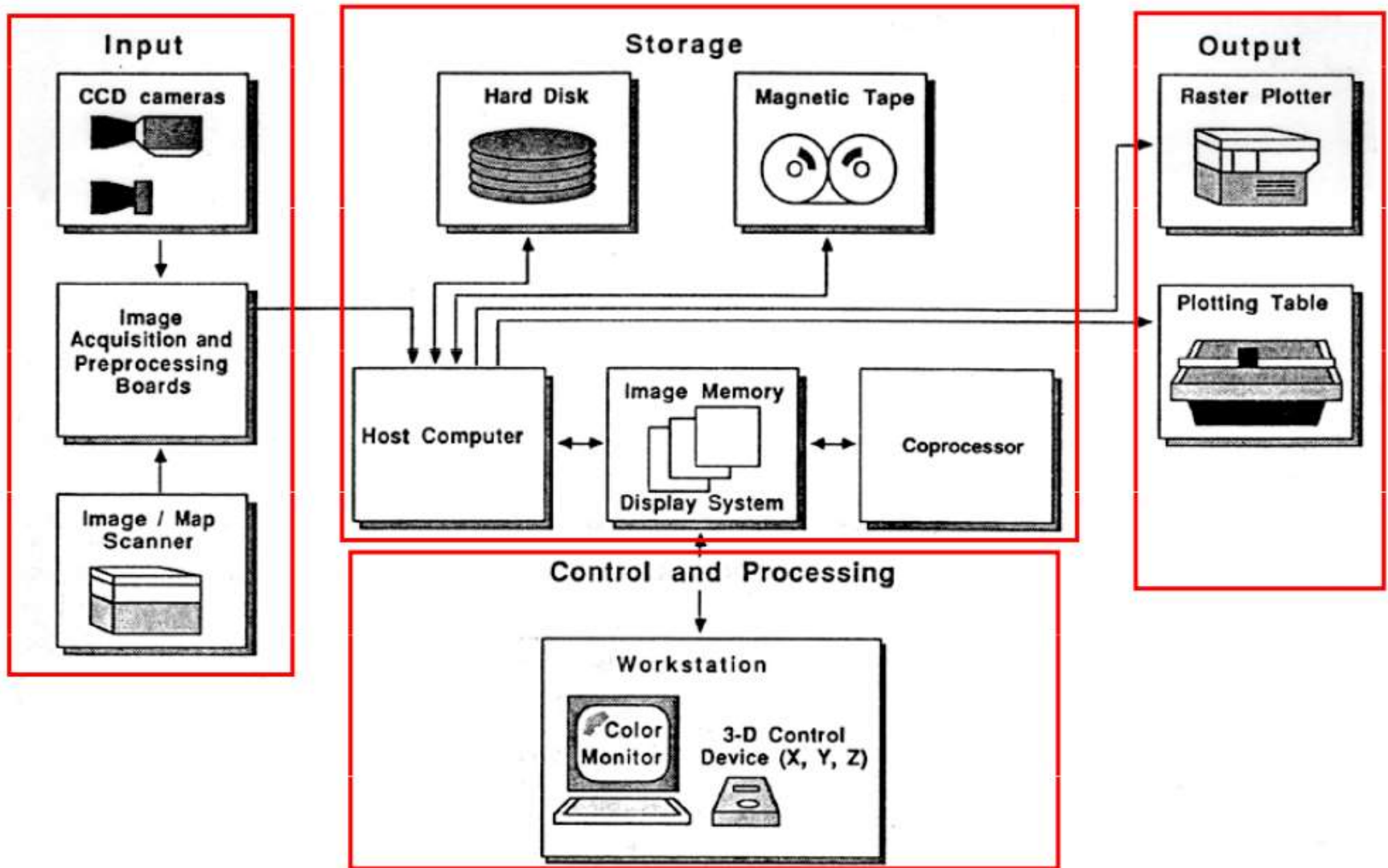
Pan-Sharpening



Generic Digital Photogrammetry Environment



Hardware architecture of a Digital Station



Digital Photogrammetric Equipments and Processes

A DPW combines computer hardware and software to allow photogrammetric operations to be carried out on digital image data.

DPWS

Digital Photogrammetric Workstation: "Hardware and software to derive photogrammetric products from digital imagery using manual and automated techniques." (ISPRS)

Typically, a DPW consists of a graphics workstation with, in most but not all cases, a stereo viewing device and a 3-D mouse.

Hardware for Digital Photogrammetry

■ Basic Hardware Requirements

- High Resolution Display
- Flexible image memory with fast access for real time roaming
- Interface capability for scanners and cameras
- Interface with output devices
- Image enhancement processor
- 3D measurement with special control devices
- Subpixel accuracy
- Data capture in a GIS or CAD

■ Stereoscopic Viewing

■ Special Hardware requirements

Software Requirements for DP

■ Standard Requirements:

- Handling Image Display
- Measurement
 - Recording Pixel Coordinates
- Determination of Orientations
 - Inner Orientation including Calibration parameters
 - Relative and absolute orientations, **B**undle Adjustment
- Transformations
- Image Processing Functions
 - Image Matching
 - Edge Detection
- Digital Rectification
- Visualization

■ Automation

VIEWING SYSTEMS

3D Viewing

The human brain requires separation of stereoimages in order to get a 3D view.



Separation method	Practical implementation
Spatial	2 monitors + stereoscope 1 monitor (split screen) + stereoscope 2 monitors + passive polarisation
Spectral	Anaglyphic   Passive polarisation
Sequential	Alternated synchronised display, active polarisation or LCD 

VIEWING SYSTEMS

The function of the viewing system of a stereoplotter is to enable the operator to view the stereomodel three dimensionally.

An **anaglyphic system** uses filters of complementary colors usually red and cyan (blue-green) to separate the left and right projections. Assume that a cyan filter is placed over the light source of the left projector while a red filter is placed over the right.

Then, if the operator views the projected images while wearing a pair of spectacles having cyan glass over the left eye and red glass over the right eye, the stereomodel can be seen in three dimension. This is simple and inexpensive. However, it prevents the use of color diapositives and causes considerable light loss, so that the model is not bright.

The **Stereo-Image Alternator (SIA)** system uses synchronized shutters to achieve stereoviewing. A shutter is placed in front of each projector lens. Also, a pair of eyepiece shutters, through which the operator must look is situated in front of the platen. The shutters are synchronized so that the left projector and left eyepiece shutters are open simultaneously while the right projector and right eyepiece shutters are closed and vice versa.

The **Polarized-Platen Viewing (PPV)** system operates similarly to the anaglyphic system except that polarizing filters are used instead of coloured filters. Filters of orthogonal polarity are placed in front of the left and right projectors and the operator wears a pair of spectacles with corresponding filters on the left and right. In contrast to the anaglyphic system, the SIA and PPV systems both cause much less light loss and both permit the use of colour diapositives.

polarizing filters

In the polarizing filters, a computer monitor is fitted with an active polarizing screen, while operator wears a simple pair of spectacles consisting of orthogonally polarizing filters.

The active polarizing screen has the capability of alternating the orientation of its polarity between horizontal and vertical (120 times per second).

The computer display has the capability of alternatively displaying the left and right images at same rate.

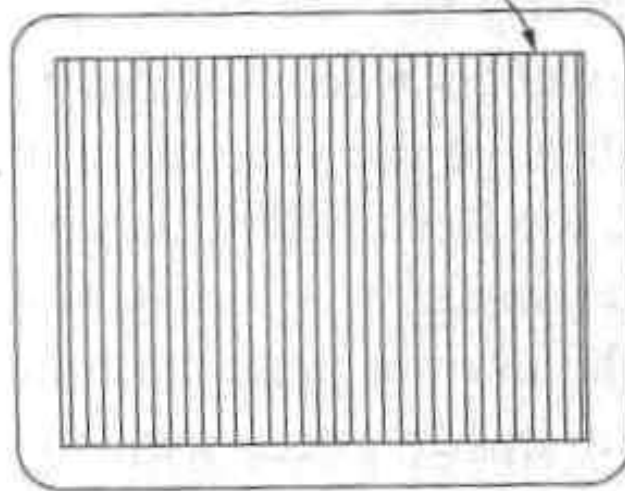
The spectacles are constructed so that the filter over one eye is oriented vertically and the other filter oriented horizontally.

At the particular instant, the polarity of the left filter of the spectacles has the same orientation as that of the screen, the left image passes through to the operator's left eye, while right eye see nothing and the same way for the right image.

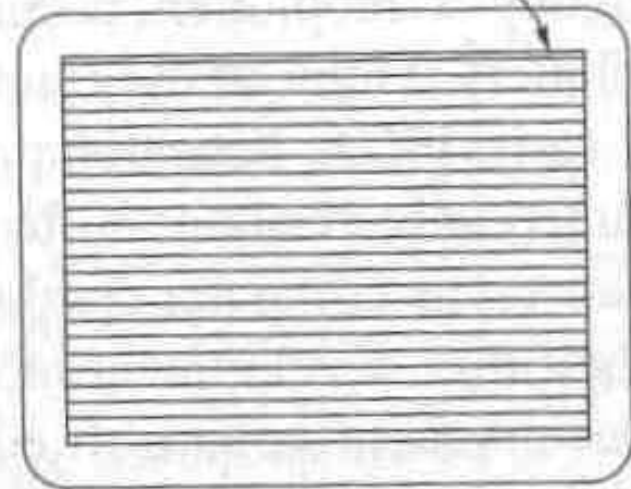
This alternating display of left and right images with synchronized alteration of the screen, the left image set with left eye and right image set with right eye and thus stereomodel will evolved.

The DPW770 system by LH systems having above setero viewing tools.

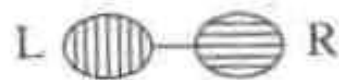
Left image displayed



Right image displayed

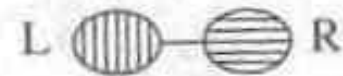


Spectacles



(a)

Spectacles



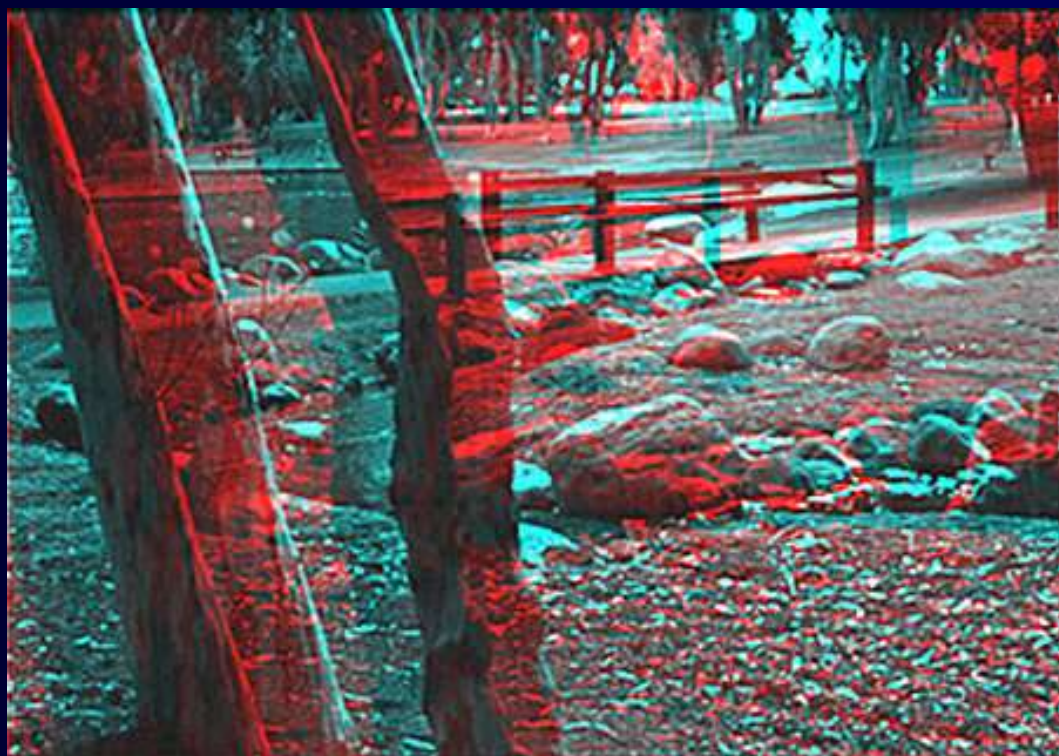
(b)

FIGURE 15-1

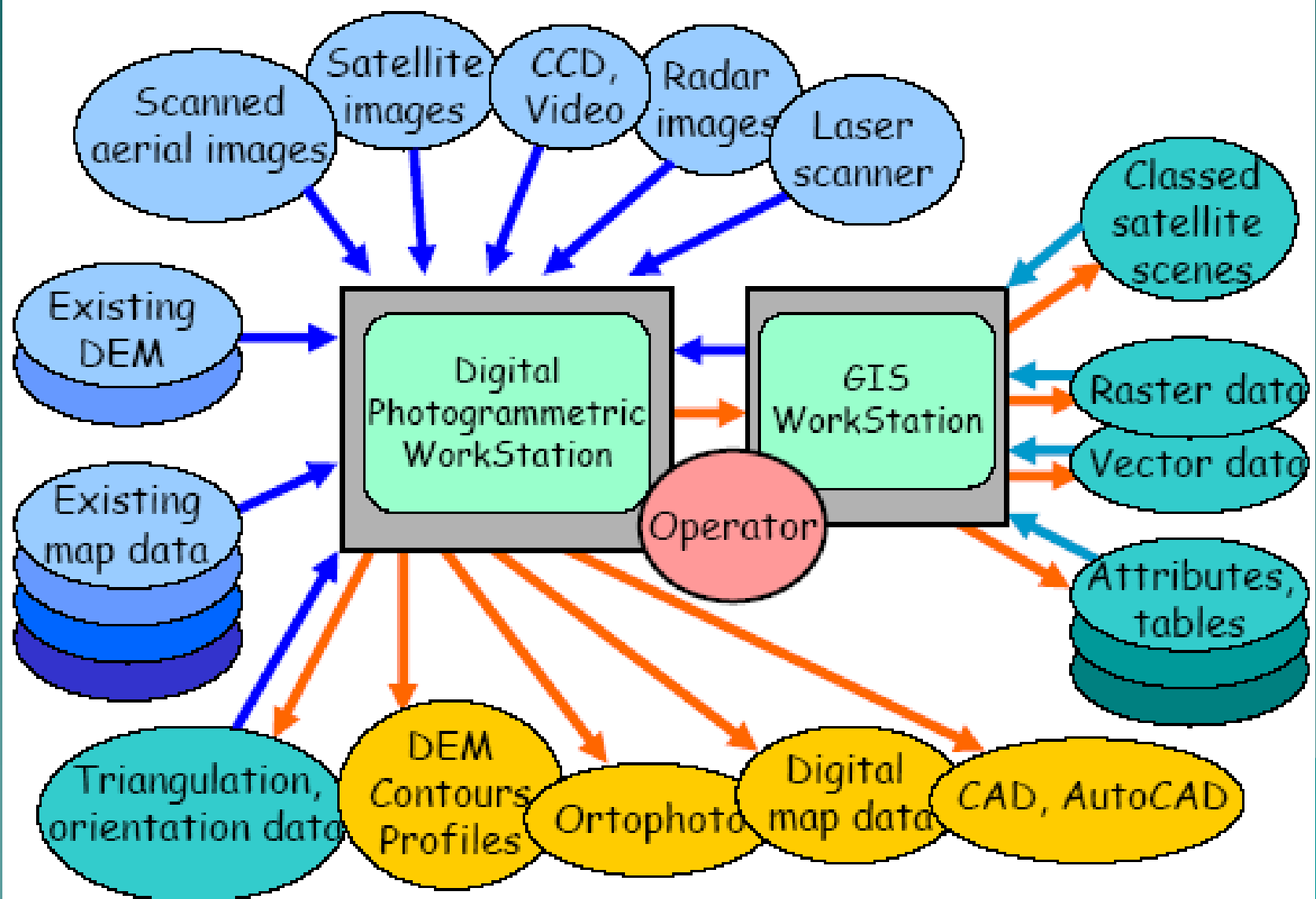
Stereoviewing principle of the active polarizing screen display.







DPWS "in the center"



Fundamentals of Digital Photogrammetry

- Why use Digital Images?
- Advantages of using Digital Images:
 - Appropriate way for displaying and Measurement
 - Stability
 - Applying image Enhancement is possible
 - Automation can be applied
 - Real time photogrammetry is not out of access

Characteristics of Digital Data

- Digitization

- Intensity
- Gray Value
- Density

- Sampling

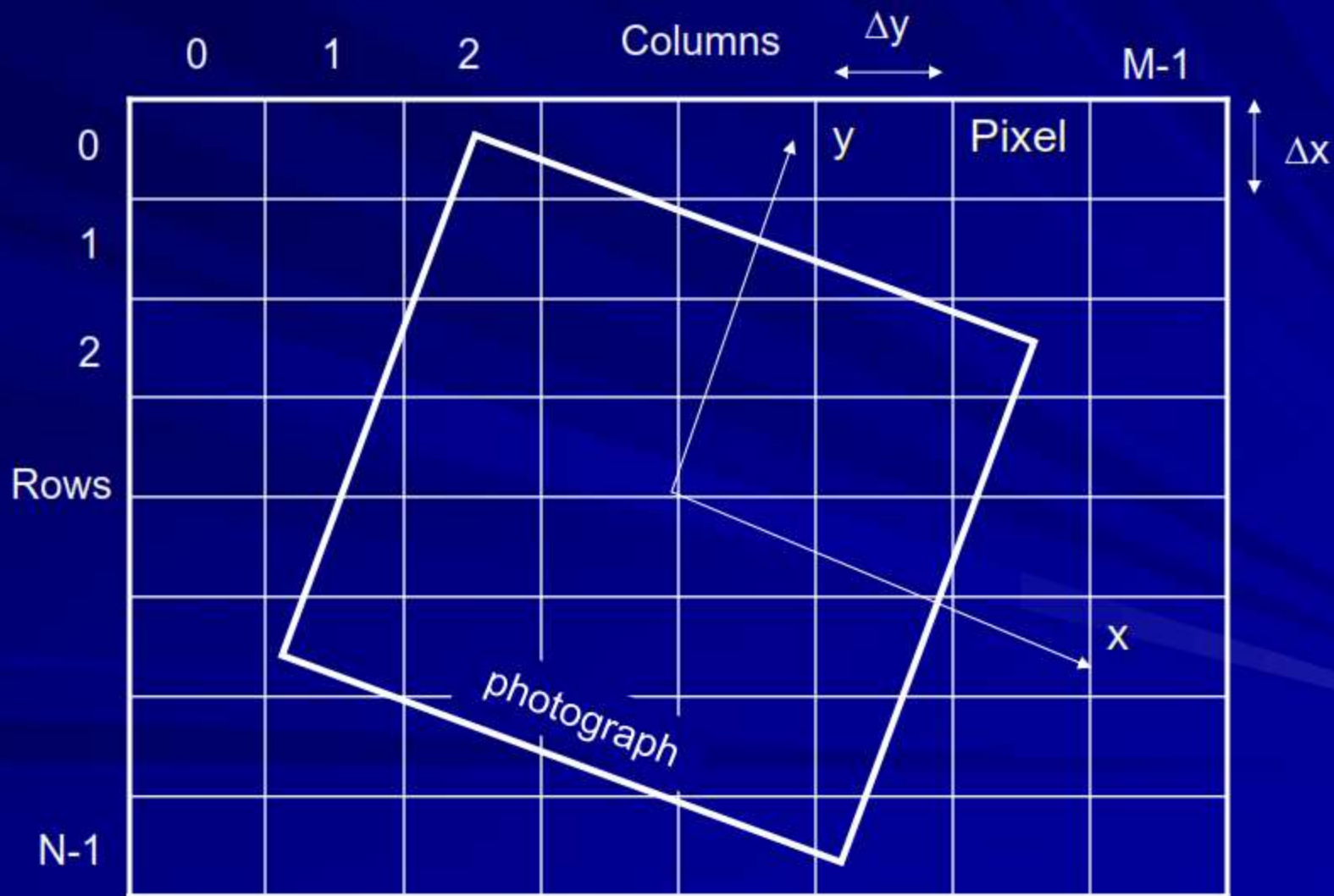
- Quantization of gray levels

- Noise

Properties of Digital Imagery

- ❖ Definition of Digital Image
- ❖ Spatial Resolution and Geometric Accuracy
- ❖ Radiometric Resolution

Definition of Digital Image



Spatial Resolution and Geometric Accuracy

Pixel Size(micron)	Number of Pixels	Storage Requirement (MB)
960	240 * 240	0.058
480	480 * 480	0.230
240	960 * 960	0.922
120	1920 * 1920	0.686
60	3840 * 3840	14.746
30	7680 * 7680	58.982
15	15360 * 15360	235.931
7.5	30720 * 30720	943.721

Classification of Processes and Tasks in Digital Photogrammetry

Category	Processes, Algorithms	Tasks
System level	Store, access, display, images	Manipulate digital imagery
Low level	Process, match images, extract features	Image processing: orientations, digital orthophoto, DEM, AT
Middle level	Group, segment images	Surface reconstruction Feature reconstruction
High level	Understand images	Object recognition Image interpretation

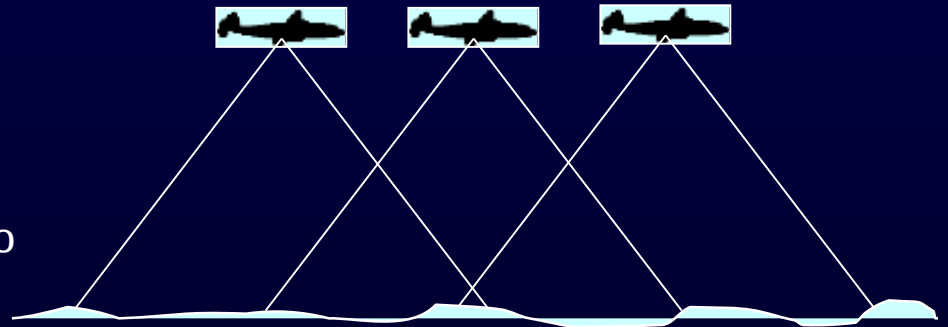
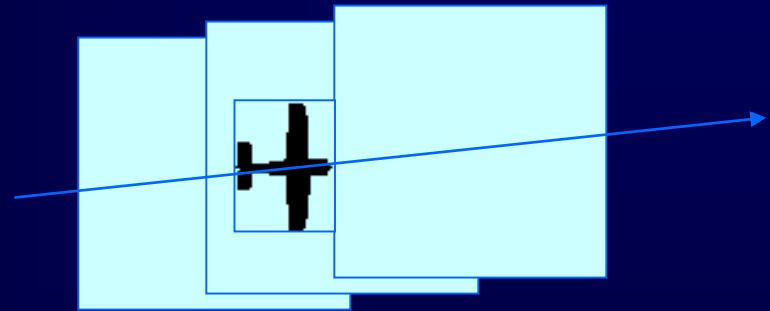
DIGITAL PHOTOGRAMMETRIC WORKFLOW

Creating a 3-D model or map is a straight and linear process that includes several steps-

- Sensor model definition
- Ground Control Point (GCP) measurement
- Automated tie point collection
- Block bundle adjustment (i.e. Aerial Triangulation)
- Automated DEM extraction
- Ortho-rectification
- 3-D feature collection and attribution

Applications of Photogrammetry

- Topographic mapping
- Creation of value added products:
 - Orthoimages
 - Digital Elevation Models
 - Virtual landscapes
- Nadir imagery is essential for mapping
- Overlap and sidelap is required to give 3D information



Example products: maps





Example of feature extraction and their perceptual organization

- features are likely to correspond to object boundaries (pixels carry no explicit information about scene)
- perceptual organization of features leads to structures that can be used to generate hypotheses about objects

Test Site

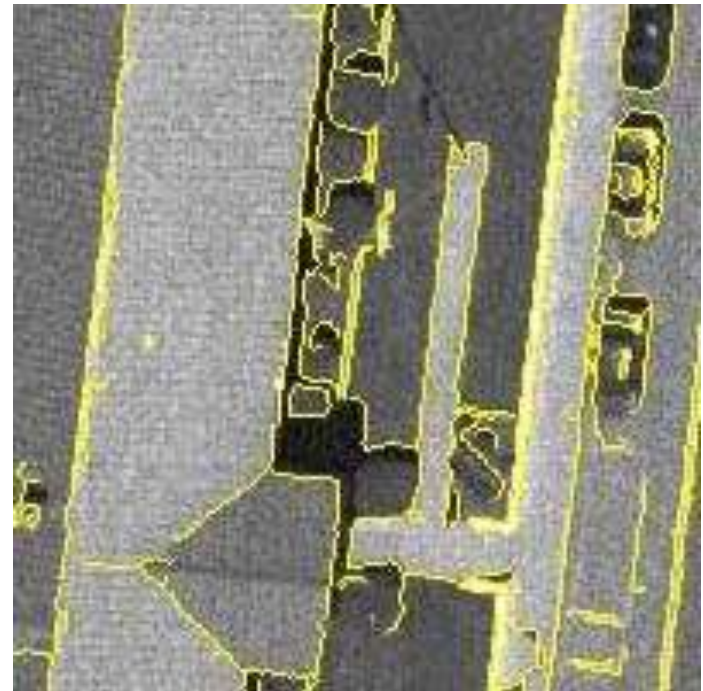
Test Site Ocean City



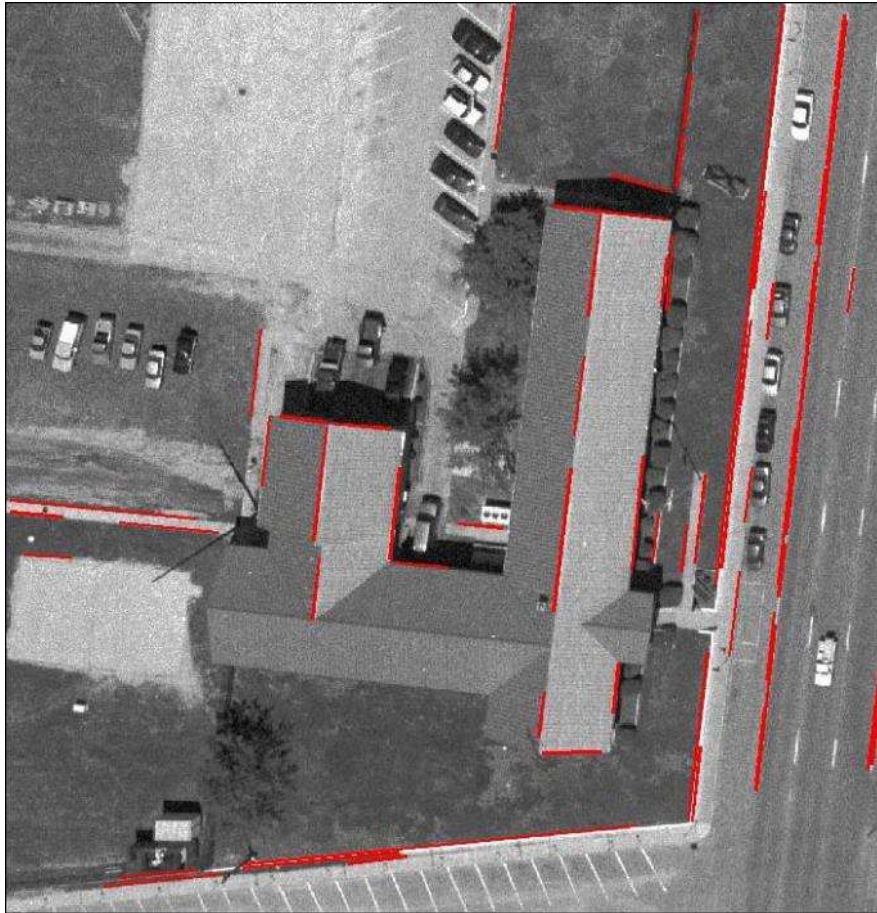
Detail View



Edge Detection



Edge Segmentation



segmentation of raw edges
into straight lines

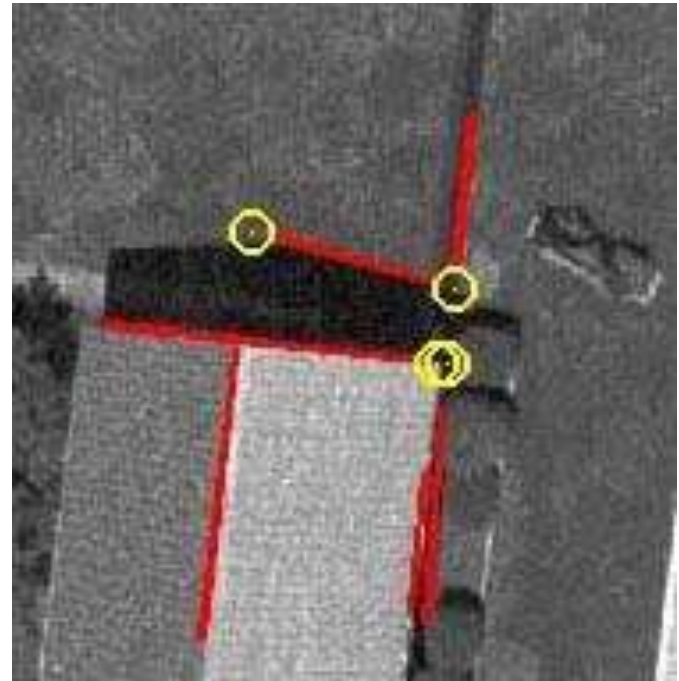
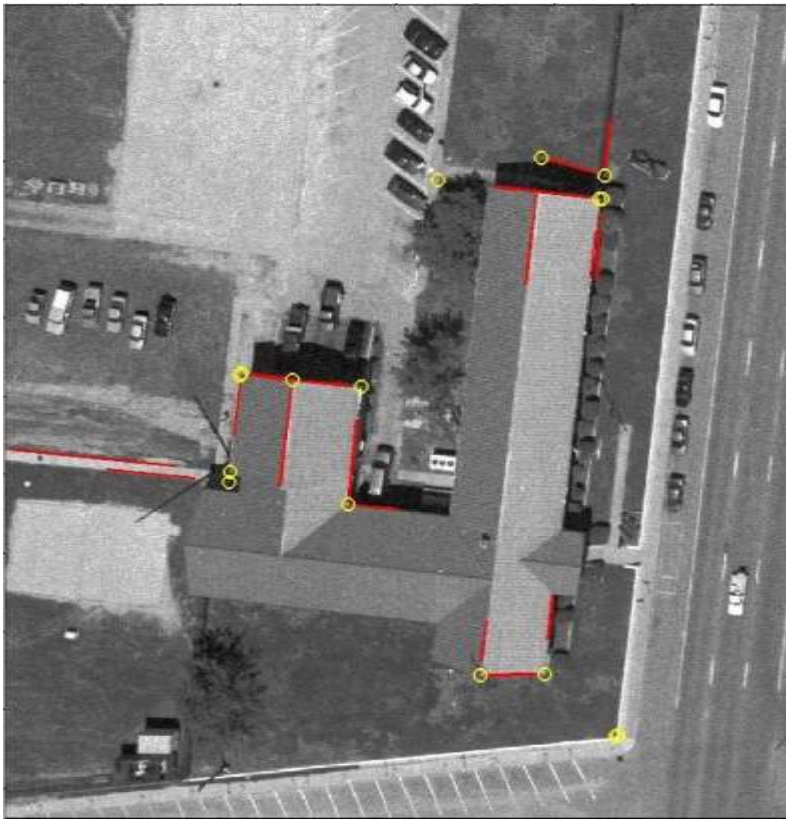
threshold criteria

straightness

length

from pixels to vectors

Grouping: Rectangular Edges and Corners

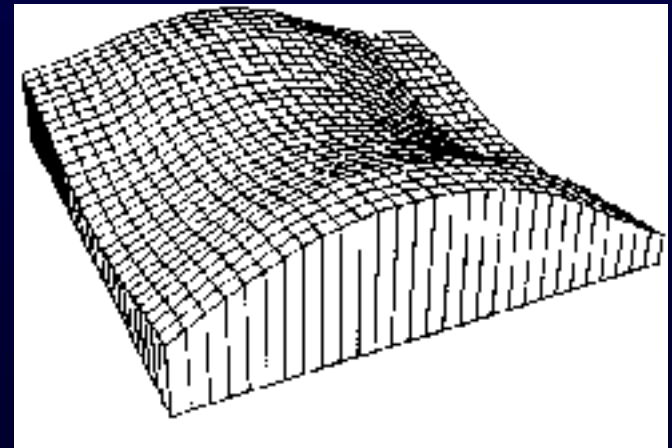
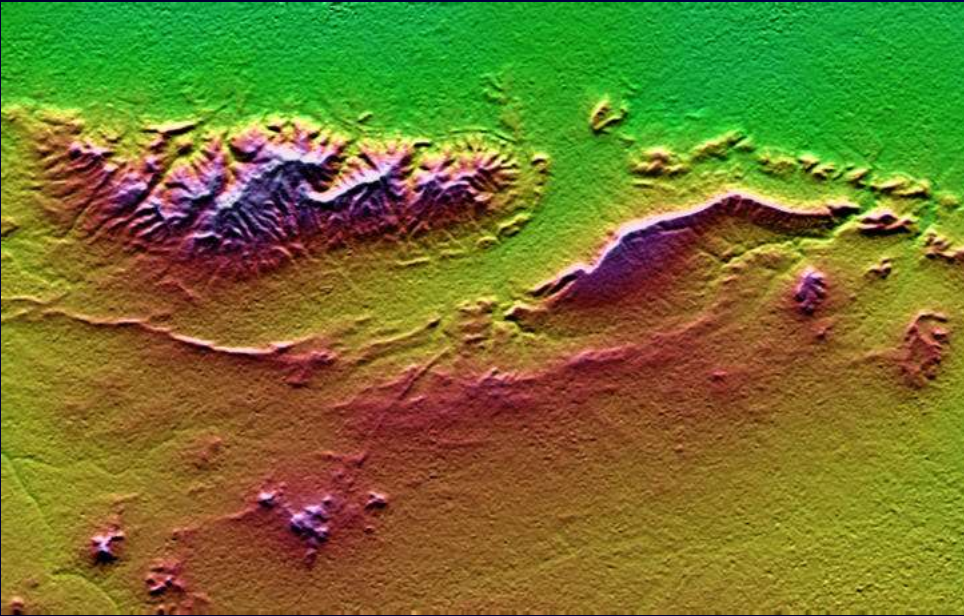




Edge Information

- segmentation and grouping are perceptual processes
- perceptual organization transforms data (edge pixels) into information (parallel edges, rectangular edges, corners,...)
- edge information enters spatial reasoning process

Example products: DTMs



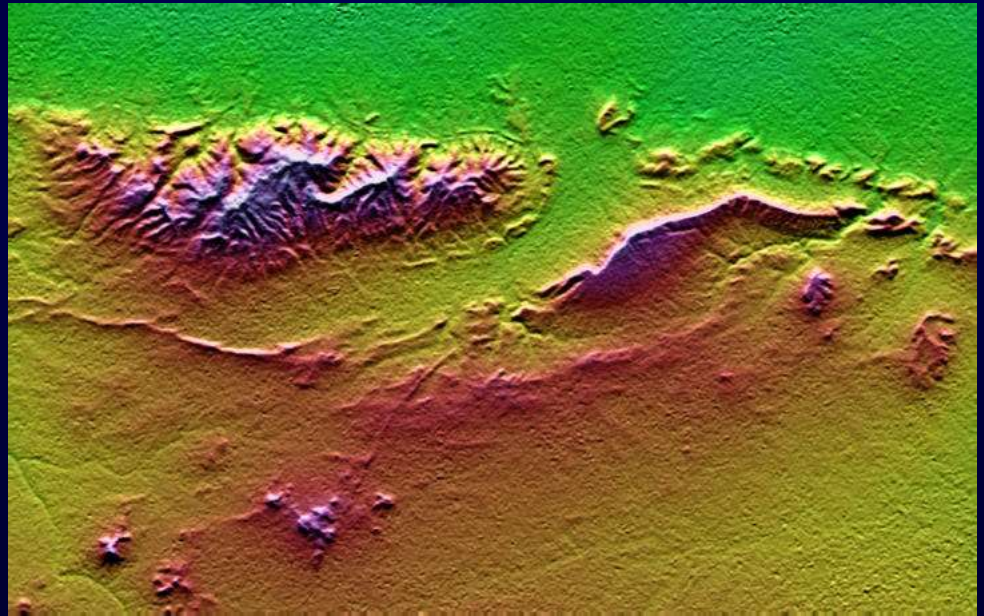
Example products: Virtual landscapes





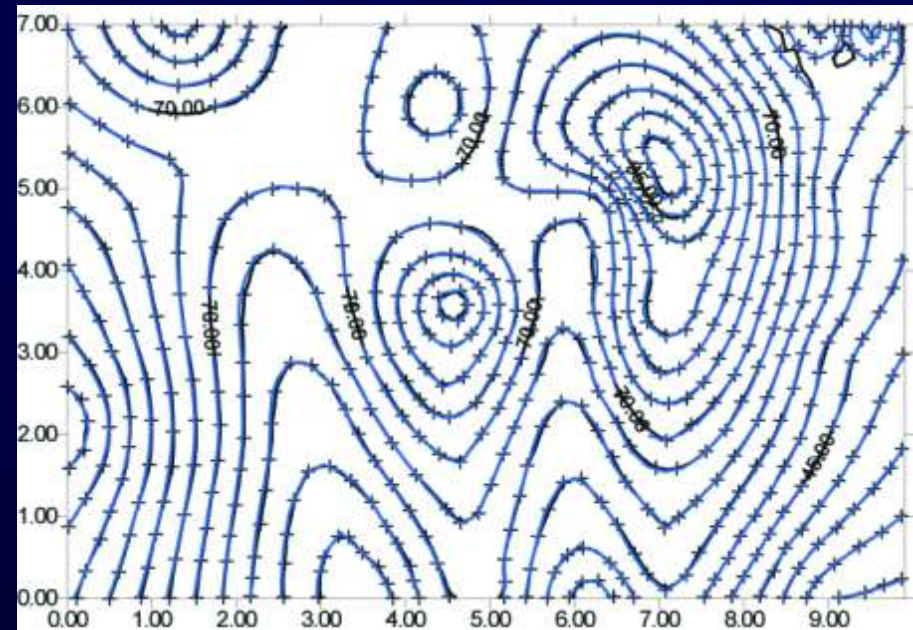
DTMs

- Sources of terrain models
 - Stereo photogrammetry
 - Interferometric radar
 - Stereo radar
 - Laser scanning
 - Digitising maps

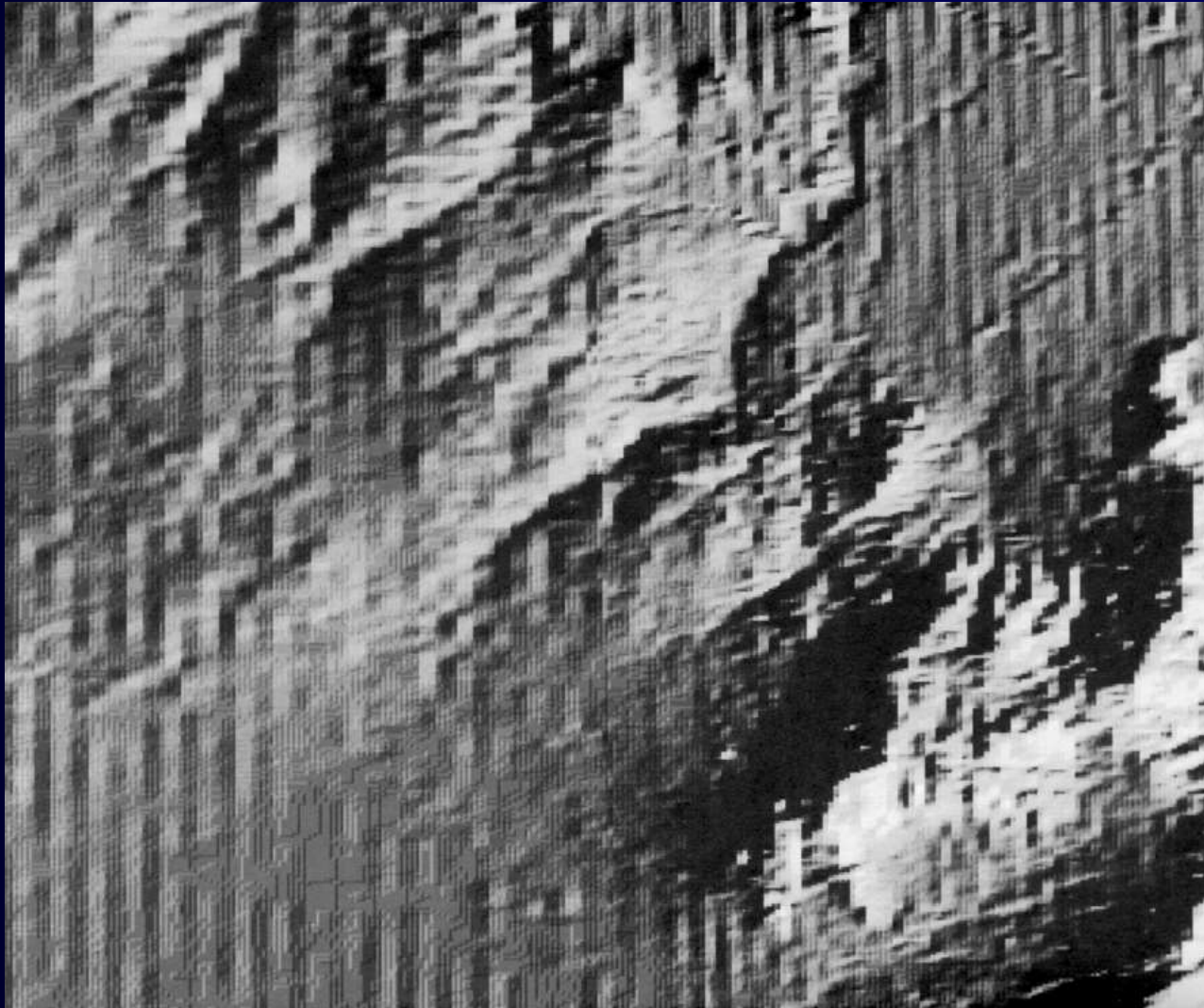


Contour digitizing

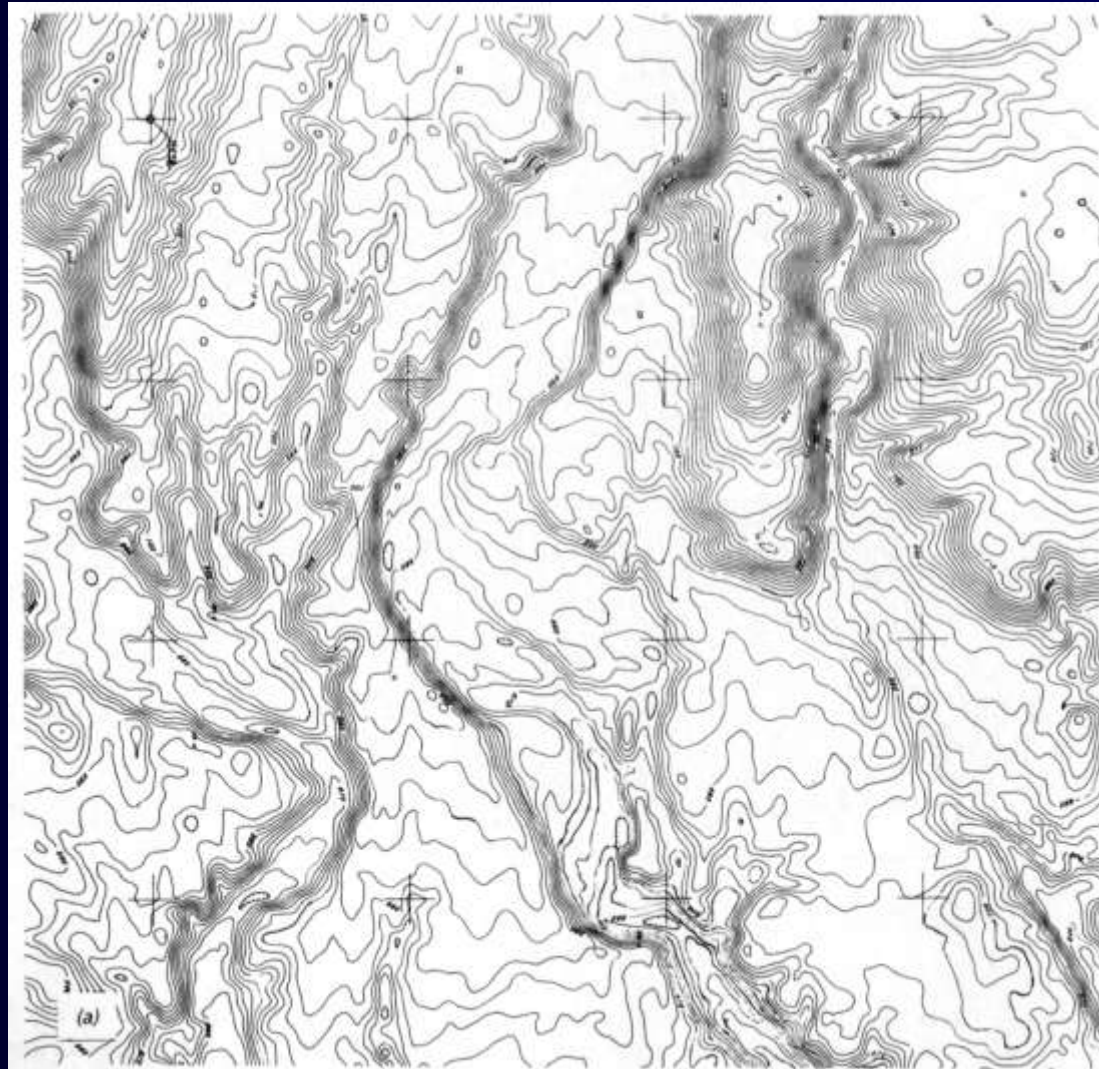
- Digital terrain model – Digitizing contour maps
- Two step procedure: click on the contours, then grid the data
- Liable to error if the DEM spacing grid is too large



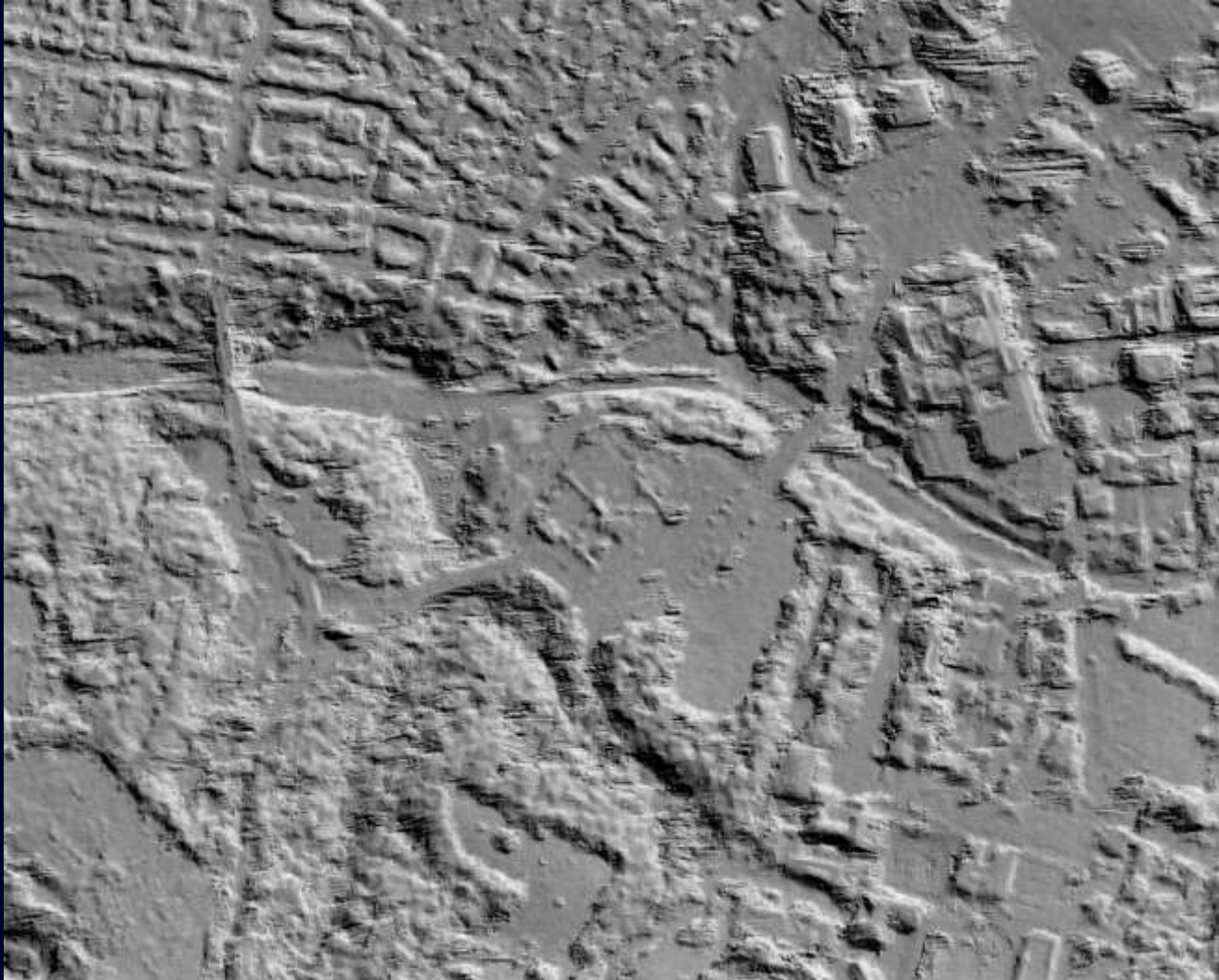
Contour digitizing



Contour map

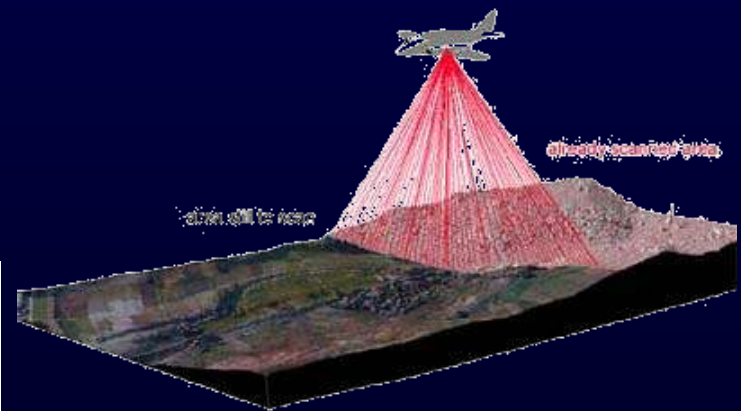
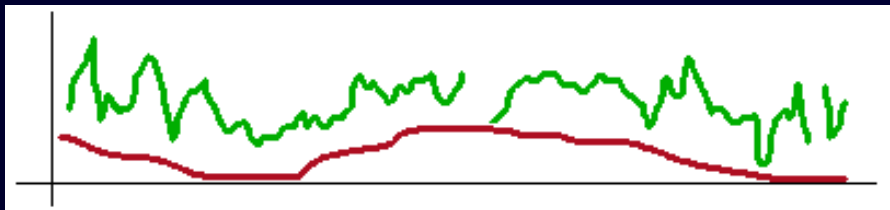


Stereo photogrammetry



Airborne laser scanning

- Digital terrain model generation – airborne laser scanning
- Laser pulse is emitted from the sensor – return journey time is measured, giving distance between sensor and target
- Location of the sensor is determined by GPS
- Therefore target can be located
- Significant post processing is required:
 - Data thinning
 - Gridding

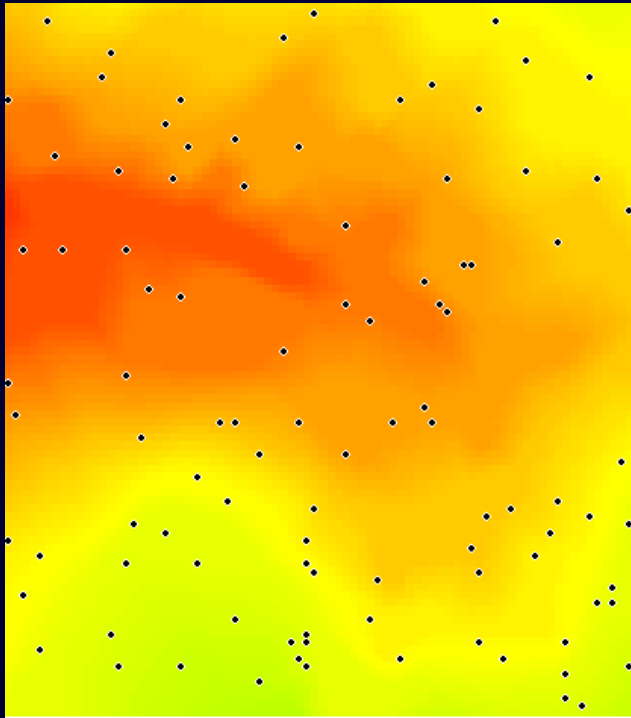


Modelling building and topological structures

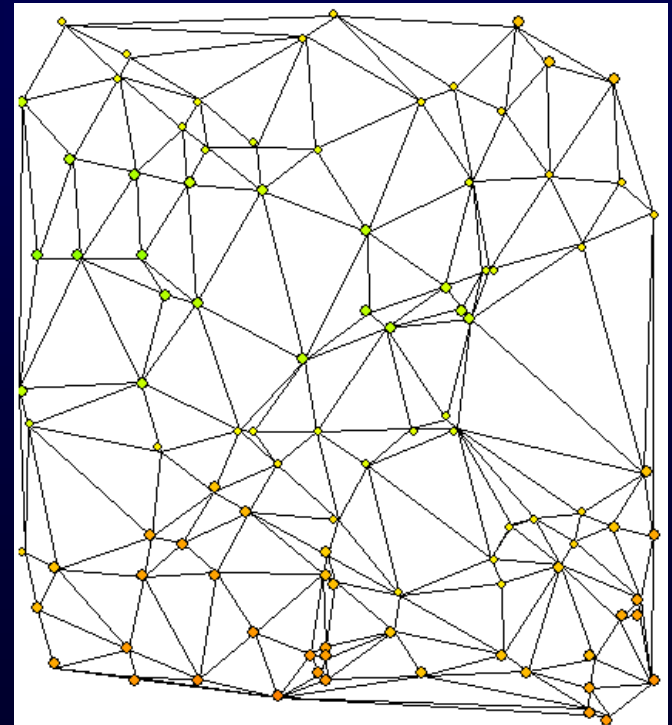
- Two main approaches:
 - Digital Elevation Models (DEMs) based on data sampled on a regular grid (lattice)
 - Triangular Irregular Networks (TINs) based on irregular sampled data and Delaunay triangulation

DEMs and TINs

DEM with sample points



TIN based on same sample points

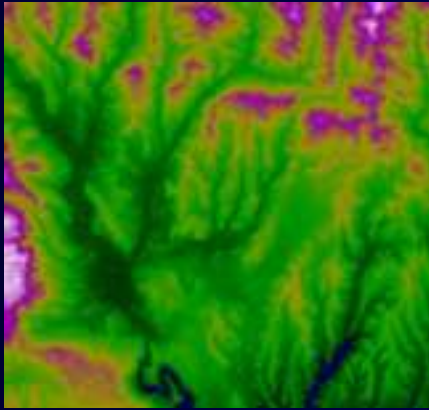


Advantages/disadvantages

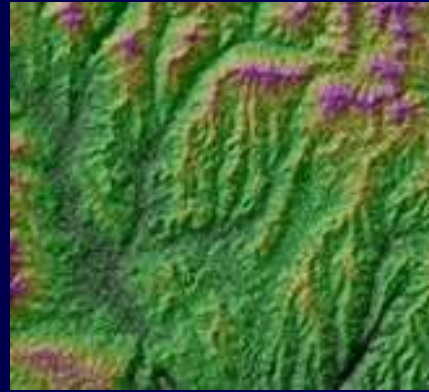
- DEMs:
 - accept data direct from digital altitude matrices
 - must be resampled if irregular data used
 - may miss complex topographic features
 - may include redundant data in low relief areas
 - less complex and CPU intensive
- TINs:
 - accept randomly sampled data without resampling
 - accept linear features such as contours and breaklines (ridges and troughs)
 - accept point features (spot heights and peaks)
 - vary density of sample points according to terrain complexity

DEM derived Variables

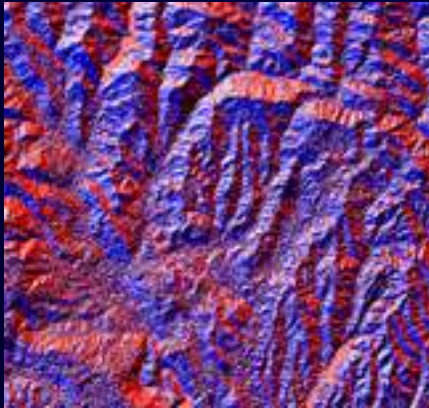
DEM



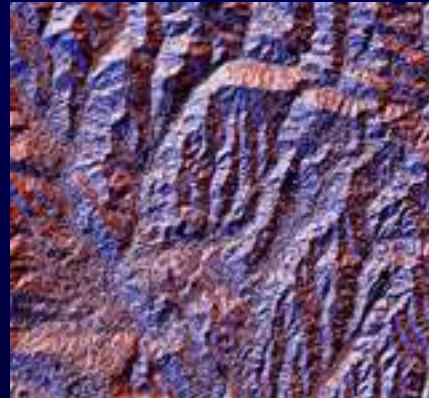
Hill shaded DEM



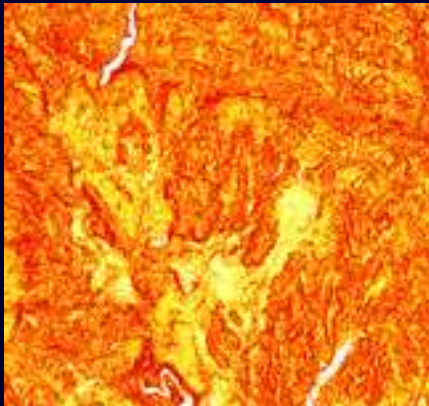
Aspect



Shaded Aspect



Slope

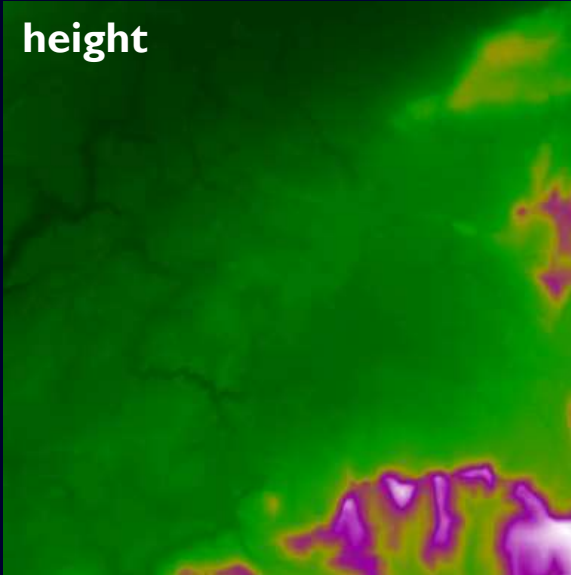


Slope draped
on DEM

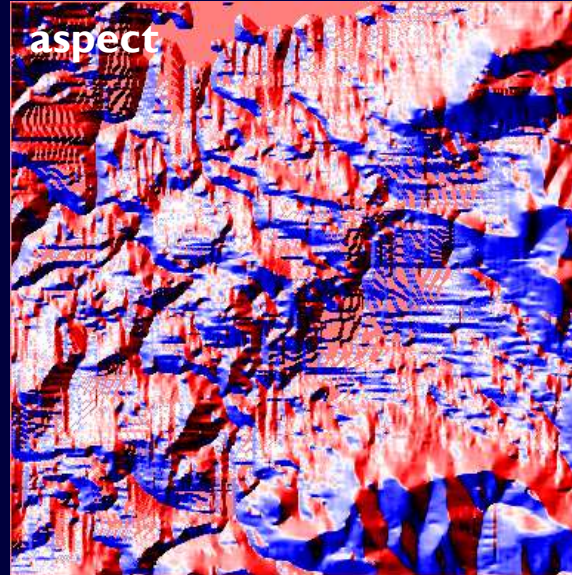


DEM derived Variables

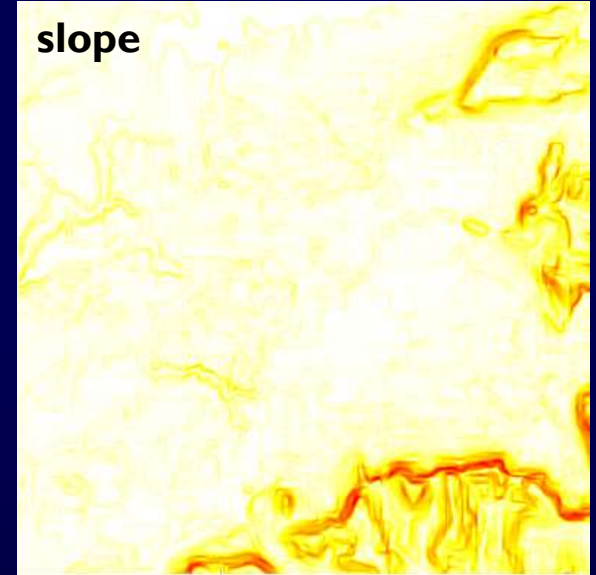
height



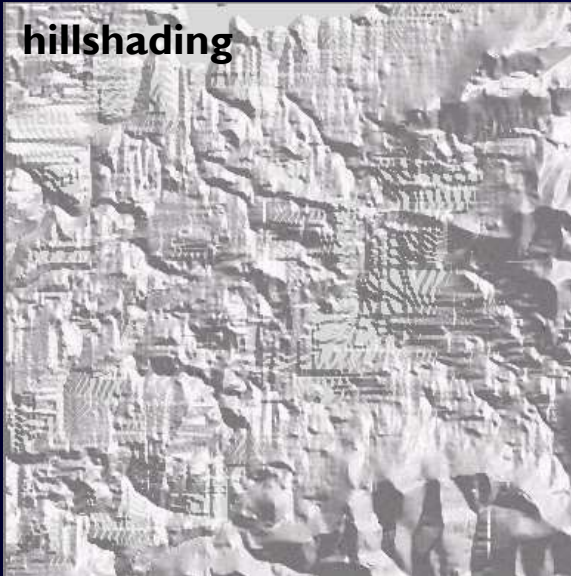
aspect



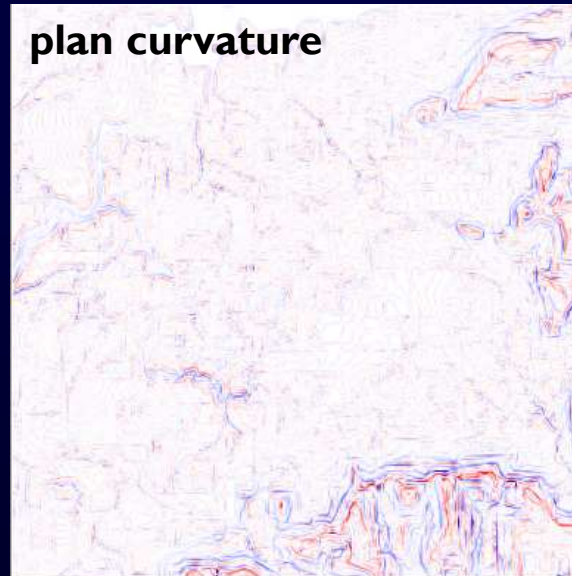
slope



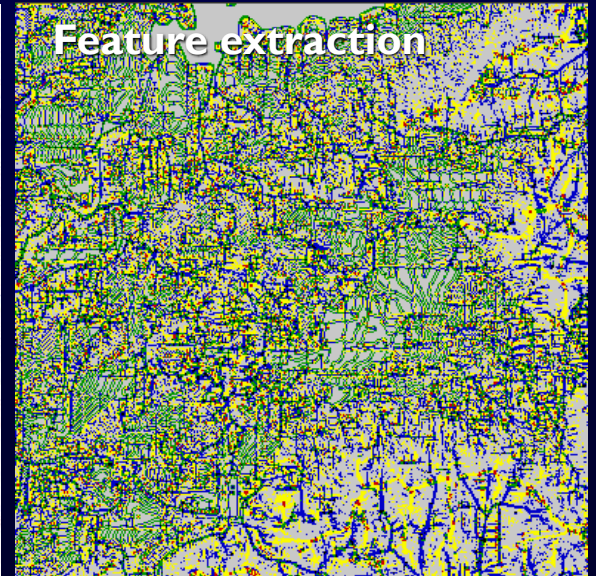
hillshading



plan curvature



Feature extraction



Leica Photogrammetry Suite

LPS 2010

ERDAS

LPS Introduction

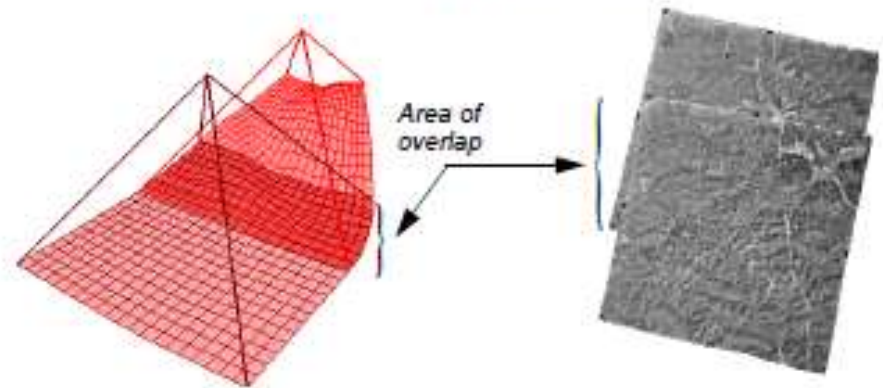
- Digital photogrammetry program that allows for
 - triangulation and
 - orthorectification

of images from various cameras and satellites

Figure 7: A Regular Rectangular Block of Aerial Photos



Figure 8: Overlapping Images



Geometric Distortions

- Raw imagery has geometric distortions
- Distortion from
 - Camera and sensor orientation
 - Terrain relief
 - Earth curvature
 - Scanning distortion
 - Measurement errors
- Thus, raw imagery cannot be used as a planimetric map

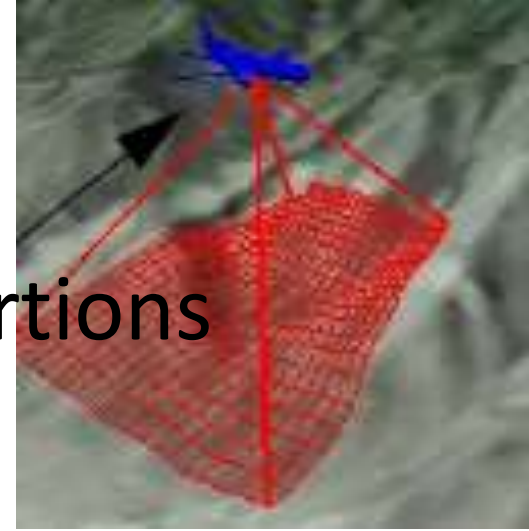
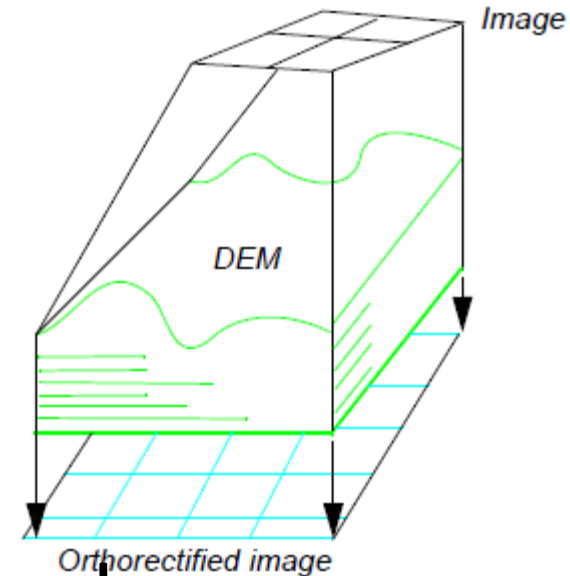


Figure 36: Orthorectification



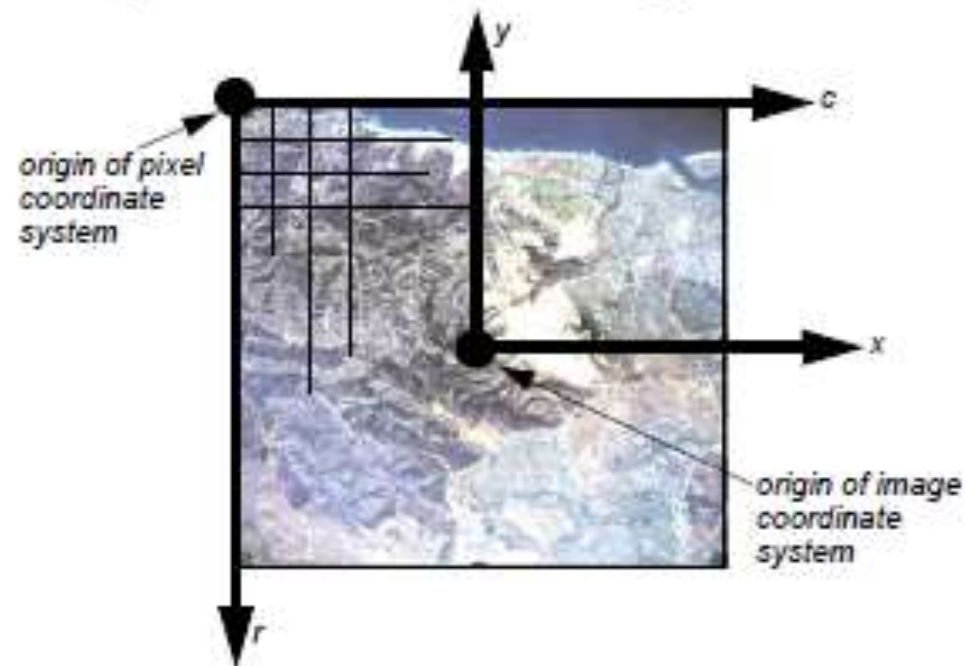
Orthorectification

- Raw images need to be rectified in order to be used for geospatial information
- Ortho photos are the leading source for geospatial data.
- Goal of orthorectification-- make images planimetrically correct. i.e., constant scale or like a map.
- STEPS in LPS...similar to CLASS work

The Major Steps in Digital Orthorectification

Interior Orientation	
Principal Point and Focal Length	..
Fiducial Marks	
Lens Distortion	
Exterior Orientation	
Rotation Matrix	
The Collinearity Equation	
Photogrammetric Solutions	..
Space Resection	
Space Forward Intersection	..
Bundle Block Adjustment	
Least Squares Adjustment	...
Self-calibrating Bundle Adjustm	
Automatic Gross Error Detection	
GCPs	
GCP Requirements	
Processing Multiple Strips of Im	
Tie Points	
Automatic Tie Point Collection	
Orthorectification	
Cell Size	

Figure 9: Pixel Coordinates vs. Image Coordinates



In the LPS labs you will....

1. Create a new project
2. Add imagery to the block file
3. Define the camera model
4. Measure the GCPs and Check points
5. Use the automatic tie point collection
6. Triangulate the images
7. Orthorectify the images
8. Use orthoimages to create geospatial data

End Goal

1. Orthorectified images of campus.
2. Use ortho images to create geospatial data that will be dropped into ArcGIS.
3. Understand how the concepts you are learning in class are utilized in a industry standard software package!

LPS Manual – We are going to start with Frame Camera Tour

This can be found w:\\farm\\cce\\fall2012\\cce201-011\\public_html\\Photogrammetry



LPS – Orthorectification

- Imagery sources that can be rectified
 - Aerial Photography
 - Satellite imagery
 - Digital and video camera
- Satellite imagery – panchromatic or multispectral
 - Landsat
 - SPOT Image
 - GeoEye

Extracting Digital Terrain Models (DTM)

- Automatic terrain extraction (elevations)
 - DEM: digital elevation models
 - TIN: triangular irregular networks
 - 3D Shape files (ESRI)

Other Features

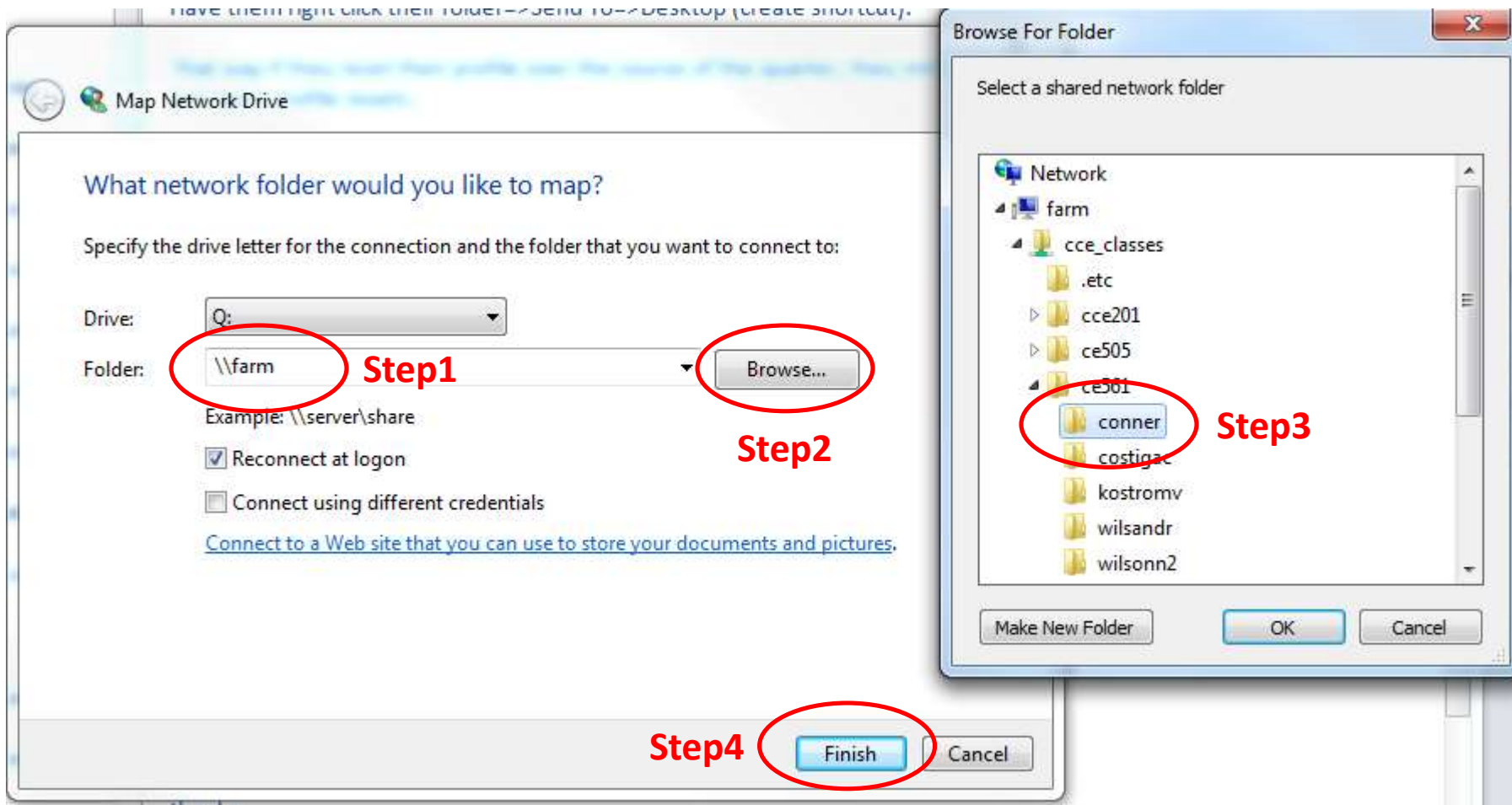
- Ortho Resampling – change cell size
- Ortho Mosaicking – merge images
- Feature Collection – collect GIS data

OSU Imagery

- Flown September 1, 2007
- Scale of printed photos 1"= 400'
- Scanning Resolution: 25 micron dpi
- Ground coverage: one pixel is **xx** feet on ground (0.01 m or 0.0328 ft)
- Flying Height: 850.4 meters or 2790 feet
- Names of Photos:
 - 1_4.tif
 - 1_5.tif

Lab 1

- Map Drive to FARM



Map Drive to FARM and Short Cut

- [\\farm.cce.oregonstate.edu\cce_classes\ce561\your_name](https://farm.cce.oregonstate.edu/cce_classes/ce561/your_name)
- Right click their folder=>Send To=>Desktop (this creates a shortcut).
- That way if they reset their profile over the course of the quarter, they still have a way to find it.
- Mapped drives always get lost upon profile resets.

Name

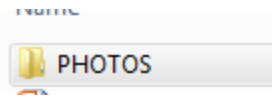
conner
costigac
kostromv
wilsandr
wilsonn2



Right-click your folder name with mouse—Send to Desktop
Create Short Cut

Step 1: Copy and Review data

- Go to classes and COPY folder “Photos”



- You do NOT have write privileges on CLASSES
 - **W:\cce\fall2012\cce201-001\public_html\Photogrammetry\PHOTOS**
-
- PASTE to
[\\farm.cce.oregonstate.edu\cce_classes\ce561](http://farm.cce.oregonstate.edu/cce_classes/ce561)**your name**

Review Photos in PAINT

- Open Paint and review each photo
- What is the smallest object you can discern?
- Can you estimate the cell size or resolution of the photo?
- Go to fiducials and mark down numbers and location



Step 2: LPS- New Project and Camera

- Create new project
 - Add imagery to block file
 - Define camera model
-

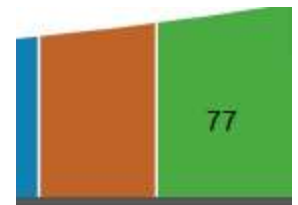
- In the LPS Manual – we will start with the Tutorial: Frame Camera

- LPS page 77
- PDF page 99

Frame Camera Tour Guide

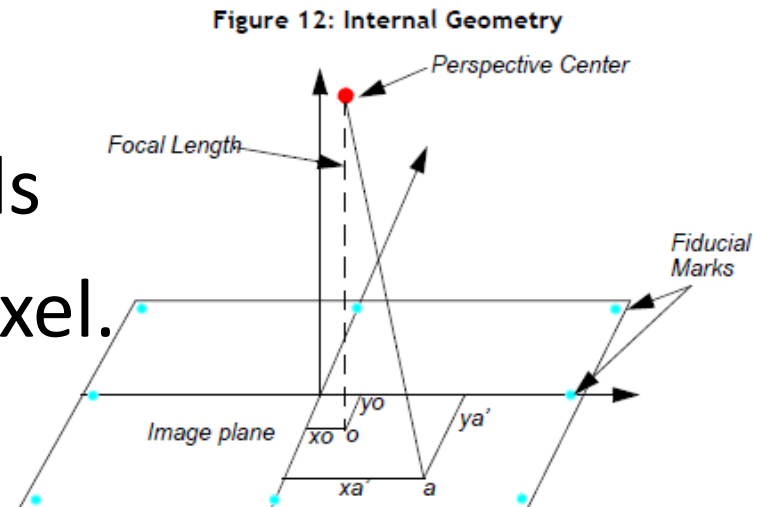
Introduction

With LPS Project Manager, you have access to many different types of geometric models with which to create a block file. This tour guide takes you through the steps with the frame camera model.



Review – Interior Orientation

- Interior orientation defines the internal geometry of camera as it existed at the time of image capture
- Image positions of fiducial marks --referenced to a pixel.



The internal geometry of a camera is defined by specifying the following variables:

- principal point
- focal length
- fiducial marks
- lens distortion

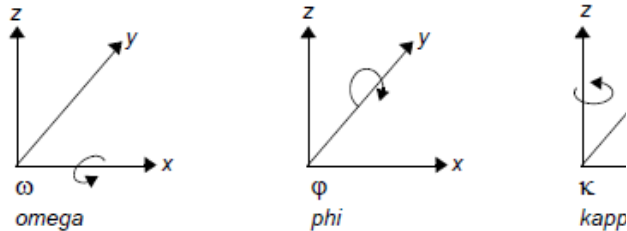
Step 3: Exterior Orientation

- Defines the relationship between ground space coordinate system (X,Y,Z) and the image space coordinate system (x,y,z)
- Three rotation angles are commonly used to define angular orientation
 - Omega (ω)
 - Phi (ϕ)
 - Kappa (κ)

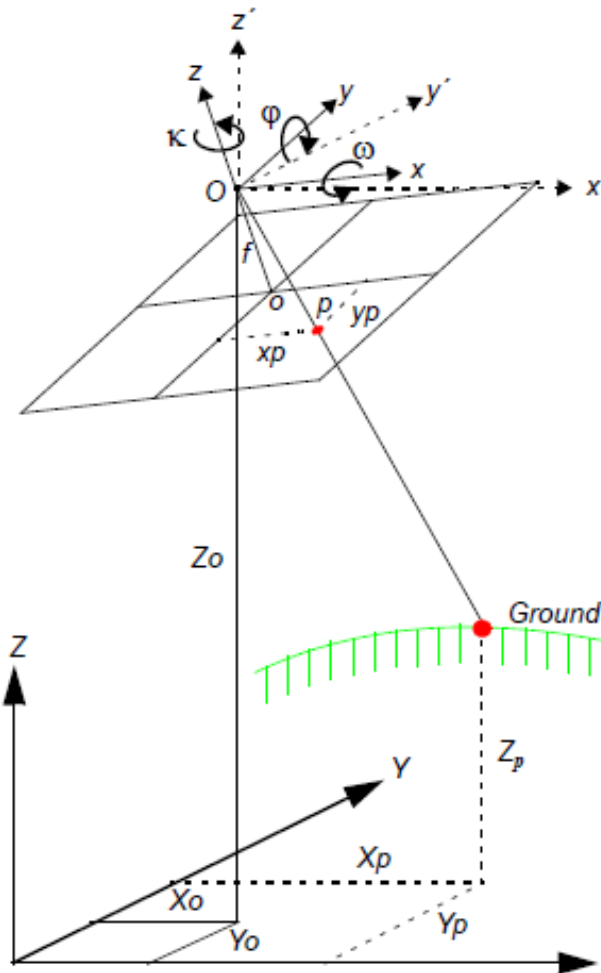
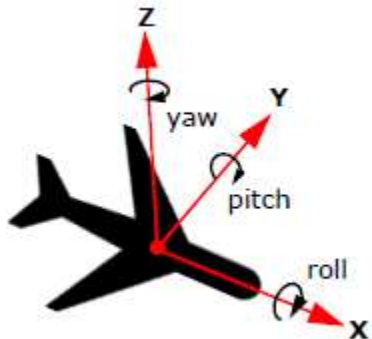
Elements of Exterior Orientation

Figure 15: Elements of Exterior Orientation

Figure 16: Omega, Phi, and Kappa



- Omega is a rotation about the photographic x-axis
- Phi is a rotation about the photographic y-axis
- Kappa is a rotation about the photographic z-axis



x, y, z - image

X, Y, Z - ground

Collinearity Condition

- Specifies that the exposure station, ground point, and corresponding image point must ALL lie along a straight line, thereby being collinear.
- Two equations comprise the collinearity condition

$$x_p - x_o = -f \left[\frac{m_{11}(X_p - X_{o_1}) + m_{12}(Y_p - Y_{o_1}) + m_{13}(Z_p - Z_{o_1})}{m_{31}(X_p - X_{o_1}) + m_{32}(Y_p - Y_{o_1}) + m_{33}(Z_p - Z_{o_1})} \right]$$

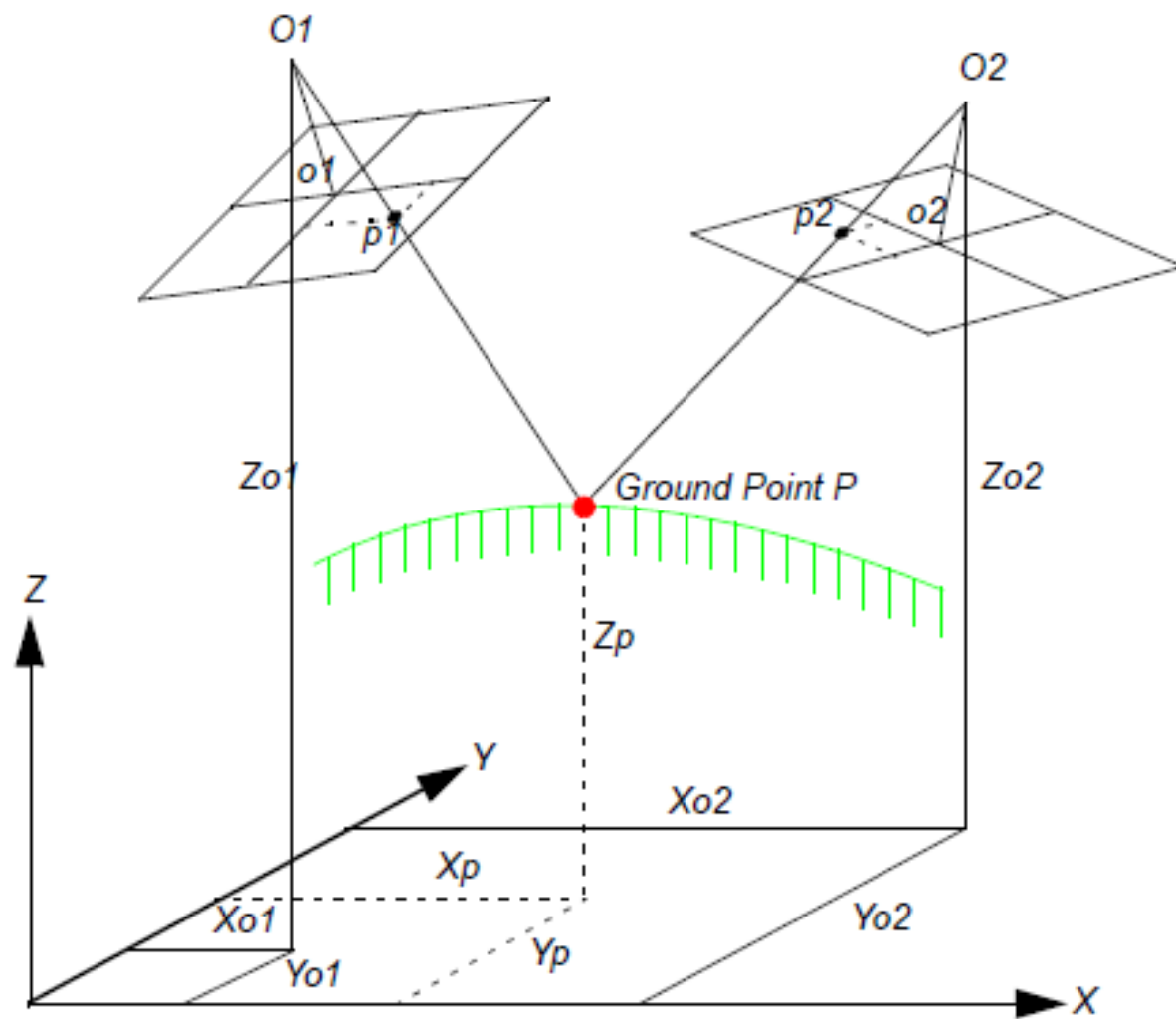
$$y_p - y_o = -f \left[\frac{m_{21}(X_p - X_{o_1}) + m_{22}(Y_p - Y_{o_1}) + m_{23}(Z_p - Z_{o_1})}{m_{31}(X_p - X_{o_1}) + m_{32}(Y_p - Y_{o_1}) + m_{33}(Z_p - Z_{o_1})} \right]$$

- This defines relationship between: camera, image and ground

Space Forward Intersection

- Determines ground coordinates in overlapping areas of two or more images.
- Collinearity condition enforced – stating that the light rays from the same points on the images intersect at same ground point.

Figure 21: Space Forward Intersection



Lab2 – Exterior Orientation

- Enter ground control ...s/b well-defined, dispersed, and permanent.
 - Utility infrastructure – manholes, fire hydrants
 - Benchmarks
 - Corner of sidewalks
 - Intersection of roads – fuzzy
- Minimum of 3 GPS – but really much more. You have 10 GCPs use 8 only.

Lab 3 – Exterior Orientation

1. Enter GCPs –

- Locate GCPs on image and then enter N/E (8 each)

2. Save 2 to use as check points (additional GCPs)

- Entered same way as GCPs
- Used to verify the accuracy of triangulation

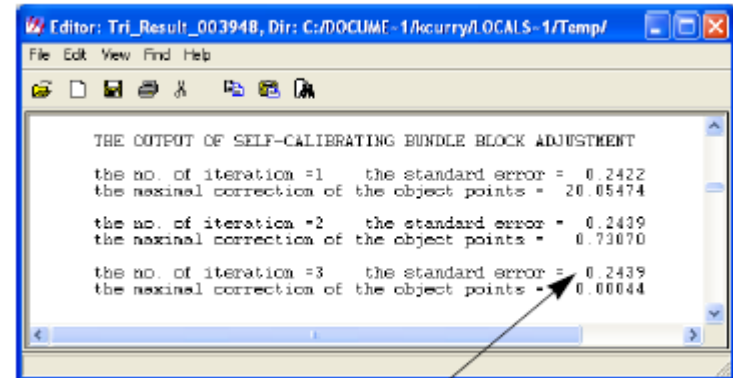
3. Perform automatic tie point generation

4. Perform aerial triangulation

5. Check and SAVE the results

Check the Results and SAVE

- Output – standard error of last iteration is most important
- Review Exterior Orientation parameters for each image: Omega, Phi, Kappa
- Note the residuals of control points and check points



```
THE OUTPUT OF SELF-CALIBRATING BUNDLE BLOCK ADJUSTMENT

the no. of iteration =1      the standard error = 0.2422
the maximal correction of the object points = 20.05474

the no. of iteration =2      the standard error = 0.2439
the maximal correction of the object points = 0.73070

the no. of iteration =3      the standard error = 0.2439
the maximal correction of the object points = 0.00044
```

The standard error of the last iteration is the most important

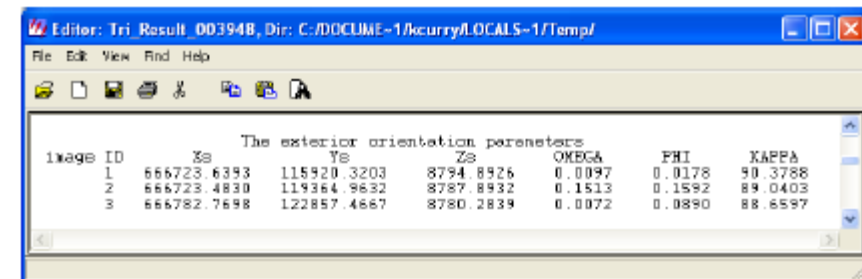
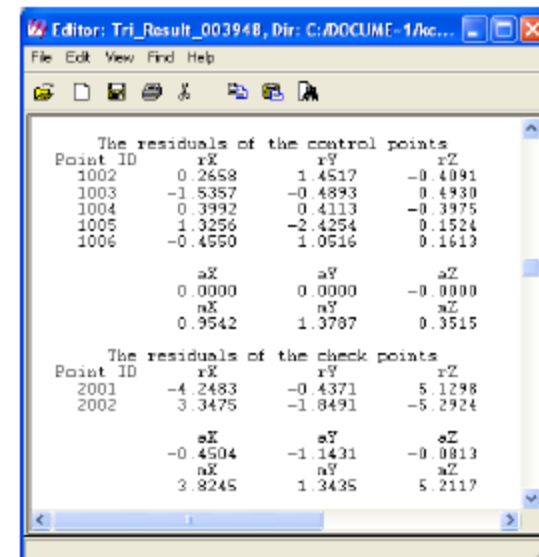


image ID	Xs	Ys	Zs	OMEGA	PHI	KAPPA
1	556723.6393	115920.3203	8794.8926	0.0097	0.0178	90.3788
2	556723.4830	119364.9632	8787.8932	0.1513	0.1592	89.0403
3	556782.7698	122857.4667	8780.2839	0.0072	0.0890	88.6597

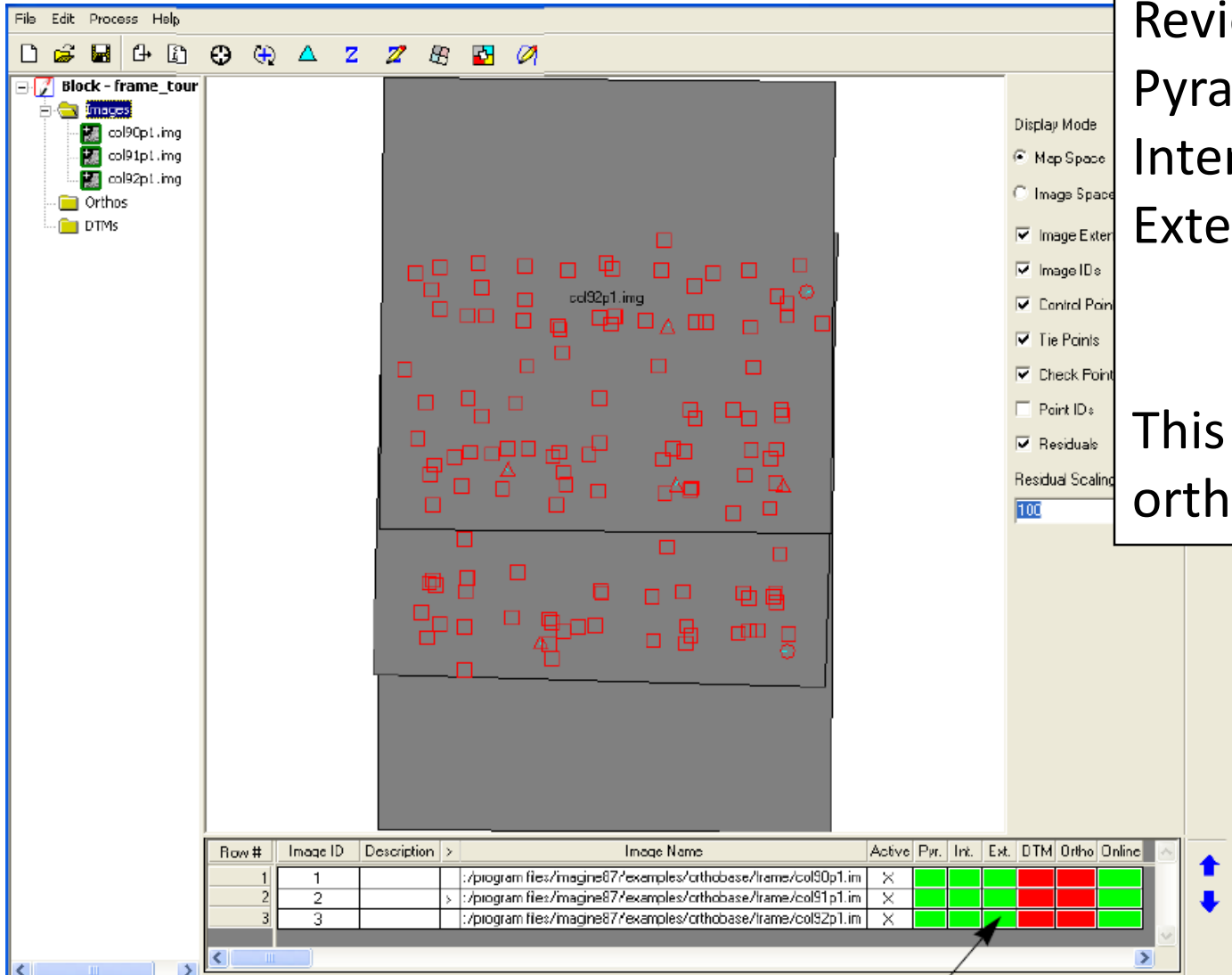


The residuals of the control points			
Point ID	rX	rY	rZ
1002	0.2658	1.4517	-0.4091
1003	-1.5357	-0.4893	0.4930
1004	0.3992	0.4113	-0.3975
1005	1.3256	-2.4254	0.1524
1006	-0.4550	1.0516	0.1613
	aX	aY	aZ
	0.0000	0.0000	-0.0000
	nX	nY	nZ
	0.9542	1.3787	0.3515
The residuals of the check points			
Point ID	rX	rY	rZ
2001	-4.2483	-0.4371	5.1298
2002	3.3475	-1.8491	-5.2924
	aX	aY	aZ
	-0.4504	-1.1431	-0.0813
	nX	nY	nZ
	3.8245	1.3435	5.2117

Lab 2 – Notes on entering GCPs

- Start on Page 99 in LPS
1. Convert GCPs to NAD83 feet and NAVD88 feet
 - divide GCPs by 0.3048 to convert meters to feet
 2. Locate GCP on image and enter NEZ in feet
 3. Locate same GCP on adjacent image
 4. Repeat for all of GCPs except for last two

LAB 3 - Orthophotos



Review: past labs
Pyramids
Interior Orientation
Exterior Orientation

This lab – create
orthophotos

Ortho Resampling

Choose DEM as the DTM Source

Set the Output Cell Sizes

The first image in the block is identified here

Ortho Resampling

General | Advanced

Input File Name: col91p1.img Active Area: 100.0%

Output File Name: (.img) orthocol91p1.img

DTM Source: DEM Vertical Units: Meters

DEM File Name: colspr_dem.img Properties...

Output Cell Sizes: X: 4.00000000 Y: 4.00000000

ULX: 661428.00000000 LRX: 671948.00000000

ULY: 124526.00000000 LRY: 114066.00000000

Output rows: 2616 columns: 2631 Recalculate...

Add... Add Multiple... Delete Show Path

Row #	Input Image Name	Active	Output Image Name	Active Area	Resample Method
1	col91p1.img	X	orthocol91p1.img	100	bilinear

1. DEM – Provides elevations For every image pixel

2. Images need to line Up with spatial Referencing of DEM

DEM- Lidar 2010, from State of Oregon - DOGAMI,
3ft horizontal resolution, vertical resolution typically ~ 4-8 inches
Vertical units (elevation) – feet

3. Output cell size are image:
Related to scale and scanning resolution
Our images – 1" = 400' and 25 microns...you can determine cell size

Scanning Resolution

Our images are 1" = 400 ft and 25 microns

Table 3: Scanning Resolutions

Photo Scale 1 to	12 microns (2117 dpi) Ground Coverage (meters)	16 microns (1588 dpi) Ground Coverage (meters)	25 microns (1016 dpi) Ground Coverage (meters)	50 microns (508 dpi) Ground Coverage (meters)	85 microns (300 dpi) Ground Coverage (meters)
1800	0.0216	0.0288	0.045	0.09	0.153
2400	0.0288	0.0384	0.060	0.12	0.204
3000	0.0360	0.0480	0.075	0.15	0.255
3600	0.0432	0.0576	0.090	0.18	0.306
4200	0.0504	0.0672	0.105	0.21	0.357
4800	0.0576	0.0768	0.120	0.24	0.408
5400	0.0648	0.0864	0.135	0.27	0.459

Resampling – Nearest Neighbor

Resample method displays here

N.N. – looks only at closest pixels

Map Projection – already set
SPCS, WGS 84, NAD83
Feet

*To add the other
images in the
block file, click
this button*

Ortho Resampling

General Advanced

Resampling Method: Nearest Neighbor

Overlap Threshold: 30.0%

☒ Ignore Value: 0.00000

Projection: State Plane
Spheroid: Clarke 1866
Zone Number: 3476
Datum: NAD27
Horizontal Units: meters

Reset Projection and Units...

Add Add Multiple... Delete

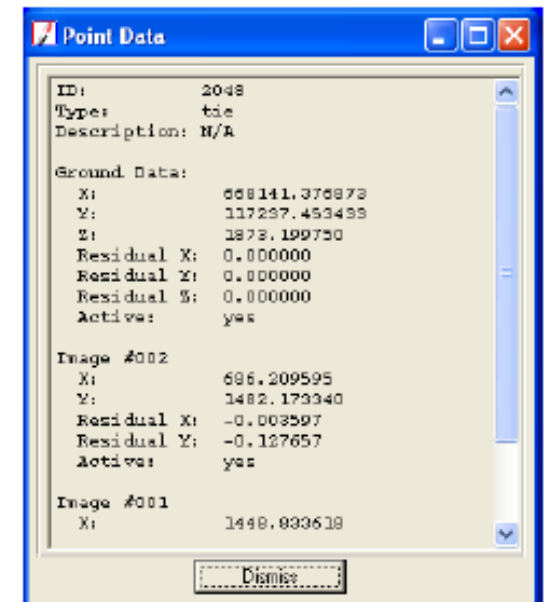
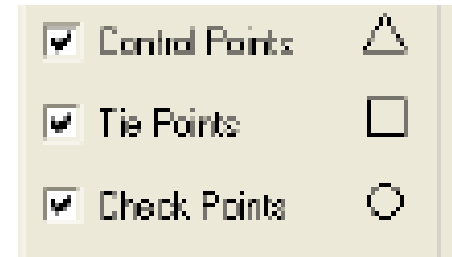
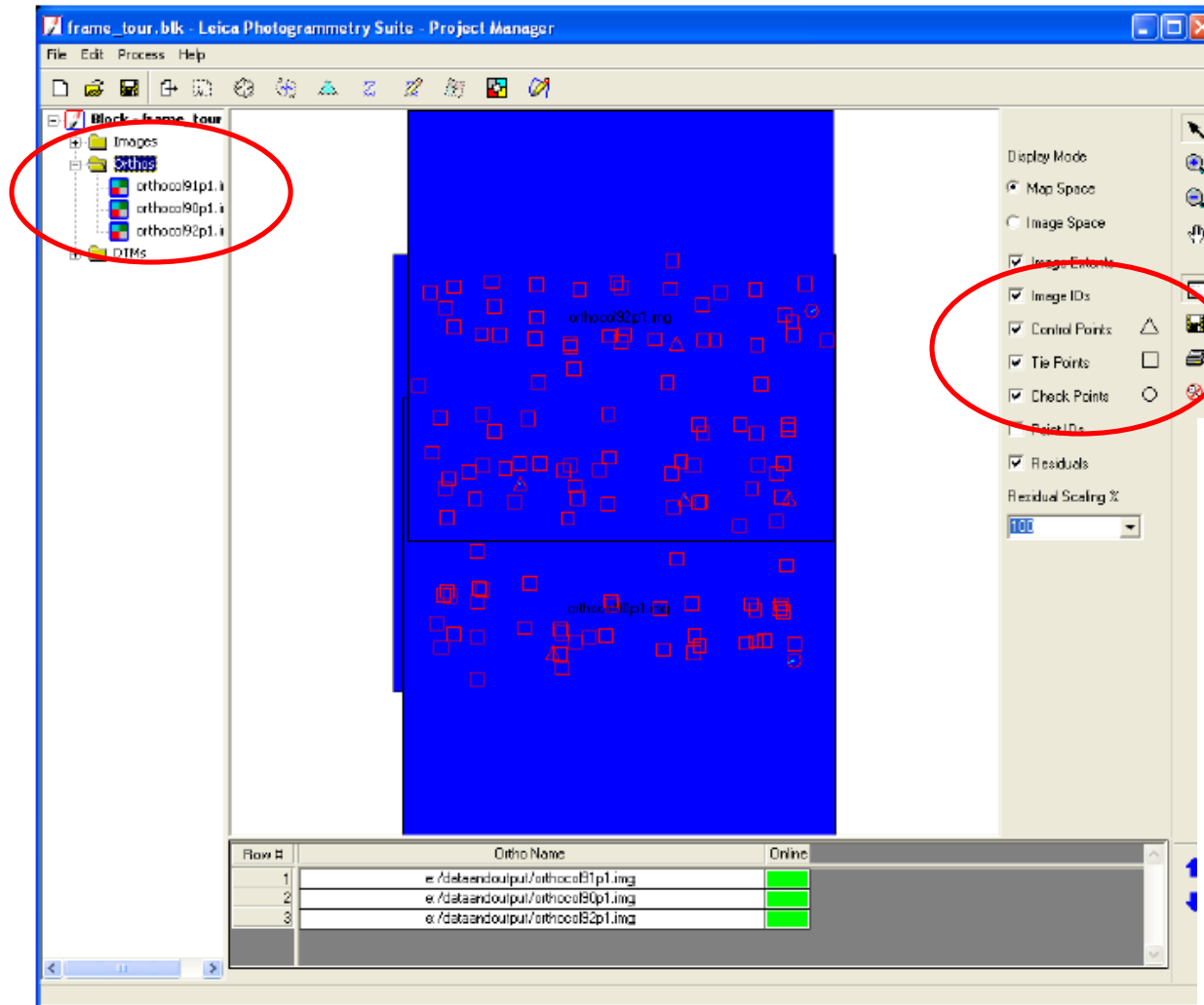
☐ Show Path

Row #	Input Image Name	>	Active	Output Image Name	Active Area	Resample Method
1	col91p1.img	>	X	orthocol91p1.img	100	nearest

Orthophotos

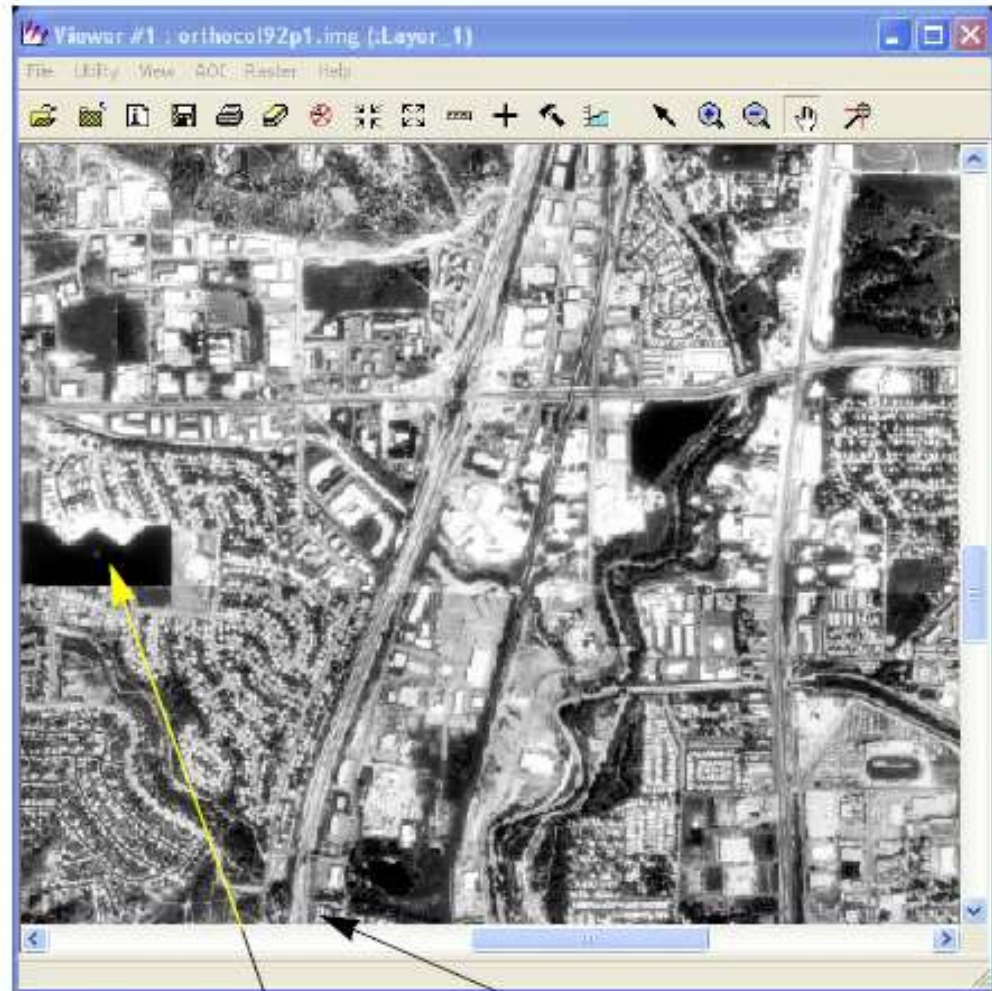
Display Graphic View

1. Click the **Orthos** folder in the Block Project Tree View.



Click on Control point and see residuals

Viewer – review results



The edge of the image can be seen here, indicated by the side fiducial mark

This road is common to both images and matches well