

Geometric potential of MOMS-02/ D2 data for point positioning, DTM and orthoimage generation

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Geometric Potential of MOMS-02/D2 Data for Point Positioning, DTM and Orthoimage Generation

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Outline

1. Introduction
2. Test Data and Ground Truth
3. Sensor Model /Geometric Point Positioning Accuracy
4. DTM Generation
5. Orthoimage Generation
6. Conclusions

Introduction

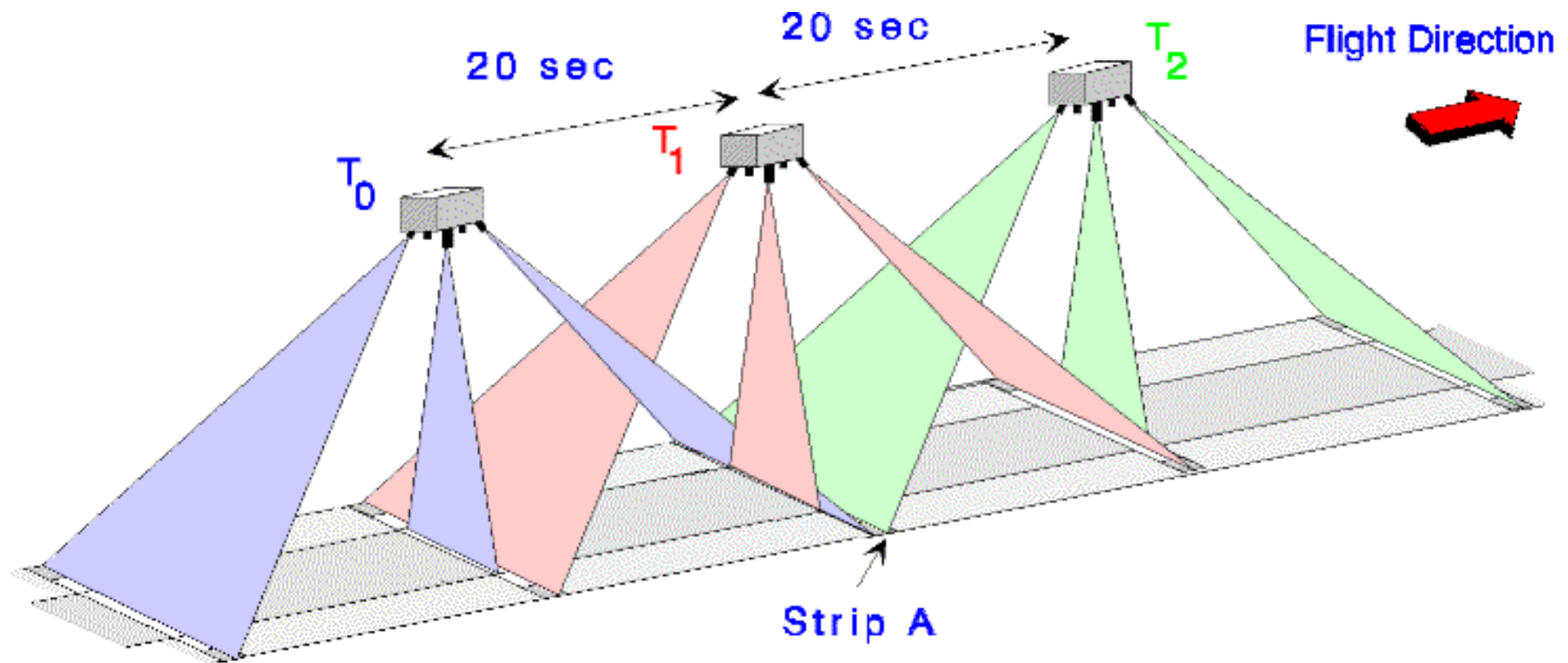
- Past and current satellite-based optical sensors:
 - linear CCDs in pushbroom mode
 - across-track (SPOT) or along-track stereo (MOMS-02)
 - geometric resolution up to 4.5 m (MOMS-02)
- Future:
 - **along-track** and across-track stereo
 - geometric resolution up to 1 m
- Improved possibilities for
 - mapping
 - DTM and orthoimage generation, orthoimage maps
 - classification and feature extraction

MOMS-02 Sensor

- High resolution imaging system with along-track stereo
- 4-channel multispectral, visible and near-infrared range
- 3-line along-track stereo (fore, aft and nadir), panchromatic
- GSD nadir: 4.5 m x 4.5 m
- GSD multispectral/oblique panchr.: 13.5 m x 13.5 m
- Convergence angle, oblique-nadir: 21.4°
- Base-height-ratio: fore-aft 0.8,
nadir-oblique 0.4
- Orbit mean altitude: 296 km

MOMS-02 Principle

Modular Optoelectronic Multispectral/Stereo Scanner 2



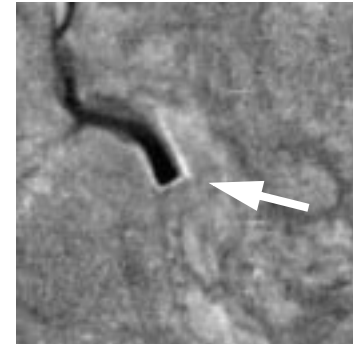
Test Data

- MOMS-02/D2 Space Shuttle Mission April/May 93
- Australia scene 17, fore - nadir -aft images
- Covered area: ca. 40 x 110 km²
- Elevation range: 200 - 300 m, few discontinuities
- Almost no vegetation and cultural features
- Data: Level 1 (radiometric corrected only)
- Image size:

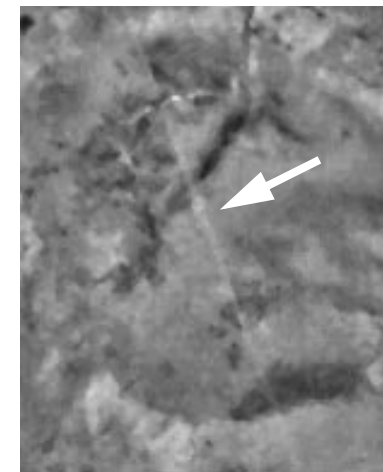
	Pixels per line	Lines
nadir	8304	24122
fore/aft	2976	8121

Ground Truth

- Ground control points
 - ca. 80 points covering the whole image
 - measured with D-GPS
 - GPS accuracy 10 cm,
actual accuracy 1 - 5 m (poor identification)
- 3D profile
 - 16 km long
 - 3228 DTM check points in 5-m interval
 - measured with roving D-GPS
 - accuracy 10 - 20 cm



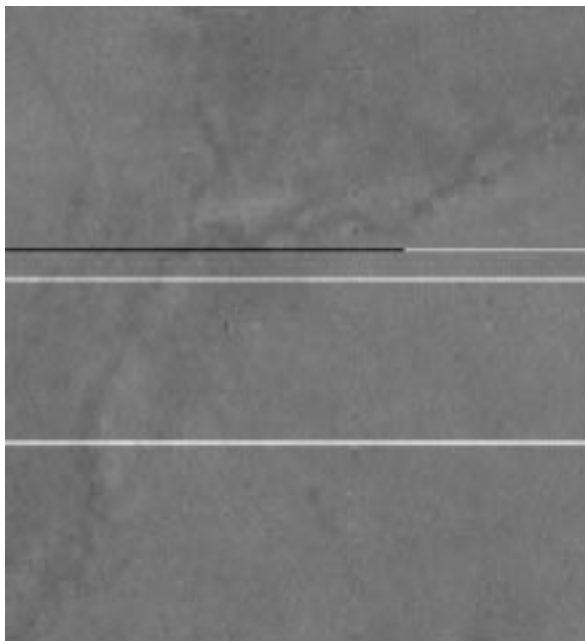
Ground control point



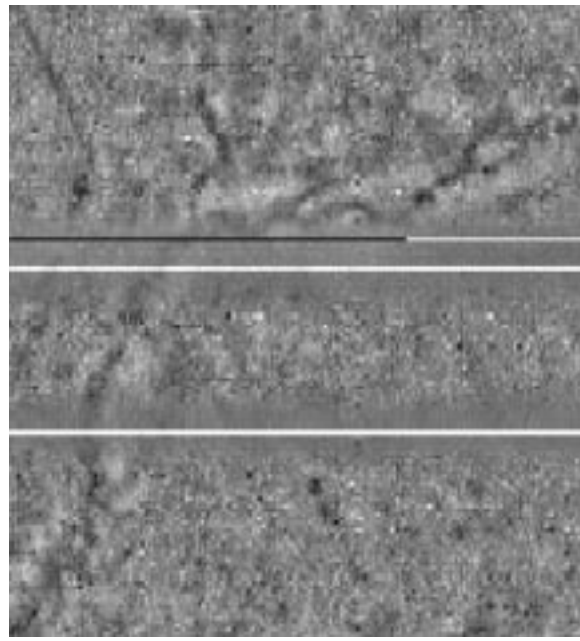
Profile along the track

Image Quality Problems

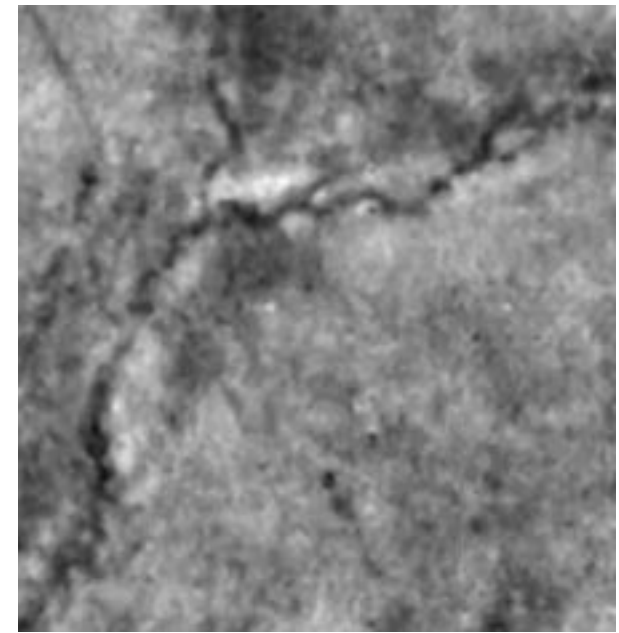
- grey level range: 50 grey values
- positive and negative spike noise, pattern noise
- blemished lines in nadir channel
- different brightness of the left and right part of nadir channel



Original (nadir)



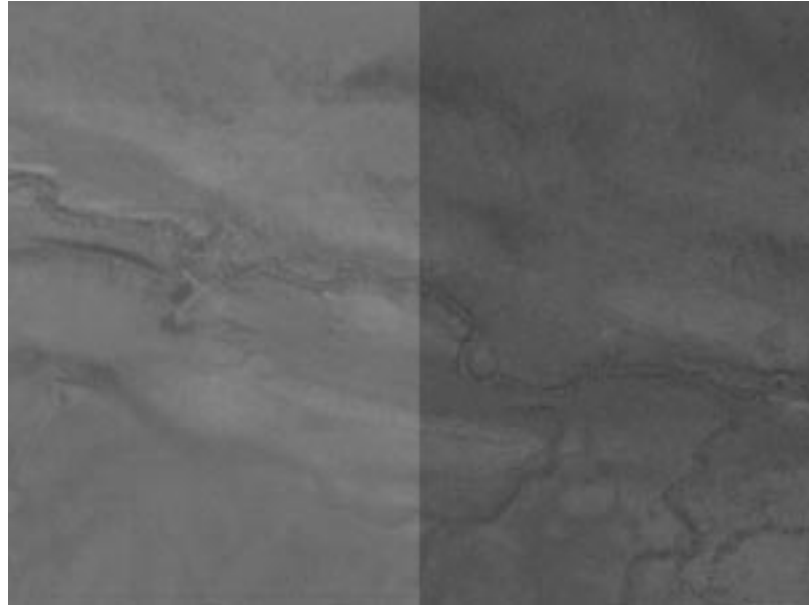
After contrast enhancement



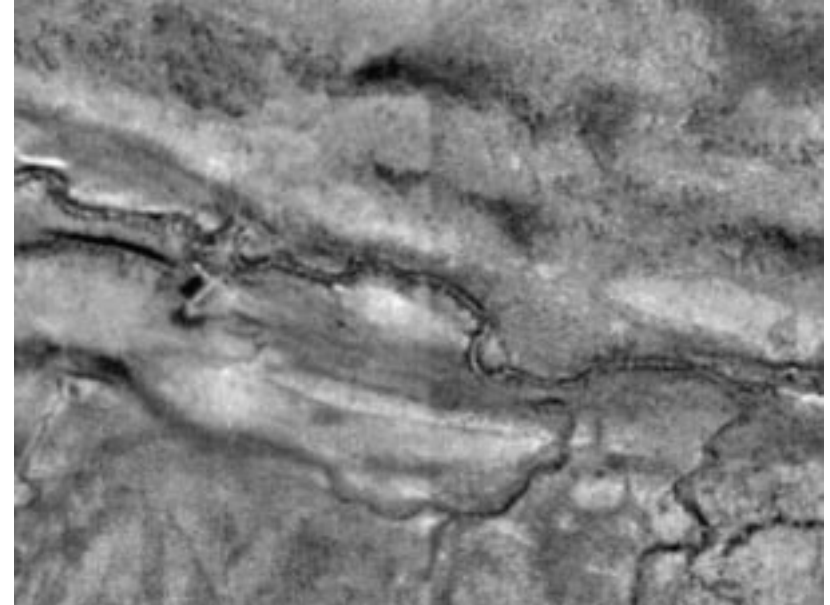
After preprocessing

Preprocessing

- for point measurement
 - strong contrast enhancement by Wallis filtering
- for DTM and orthoimage generation
 - noise reduction by median filter
 - contrast enhancement by Wallis filtering
 - special filters for nadir channel



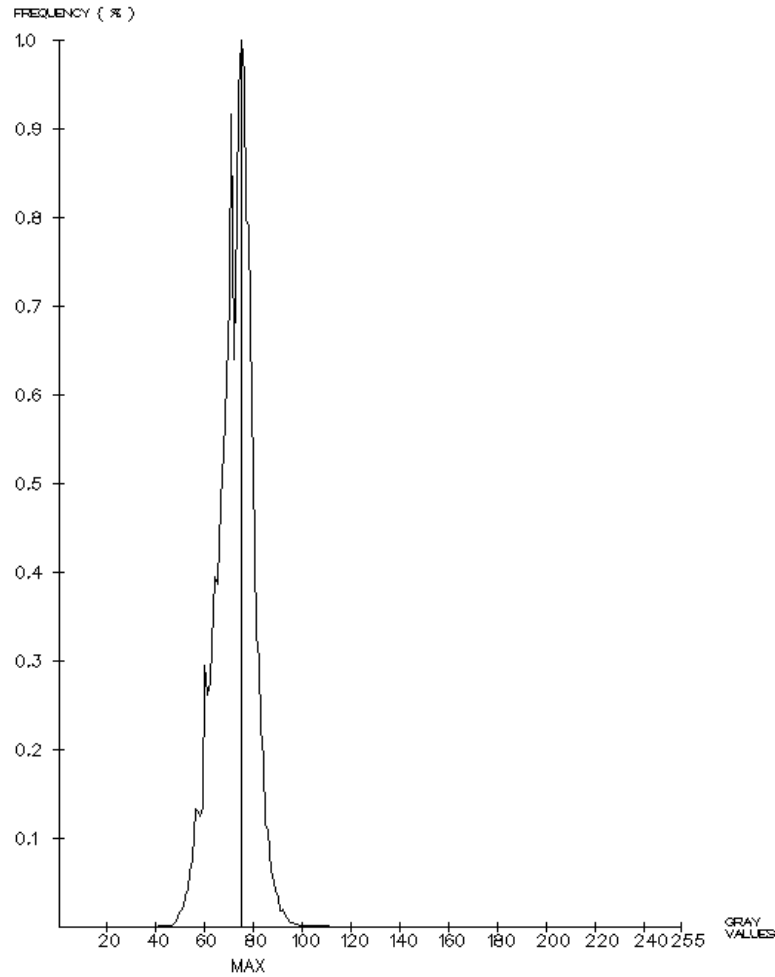
Original (nadir)



After preprocessing

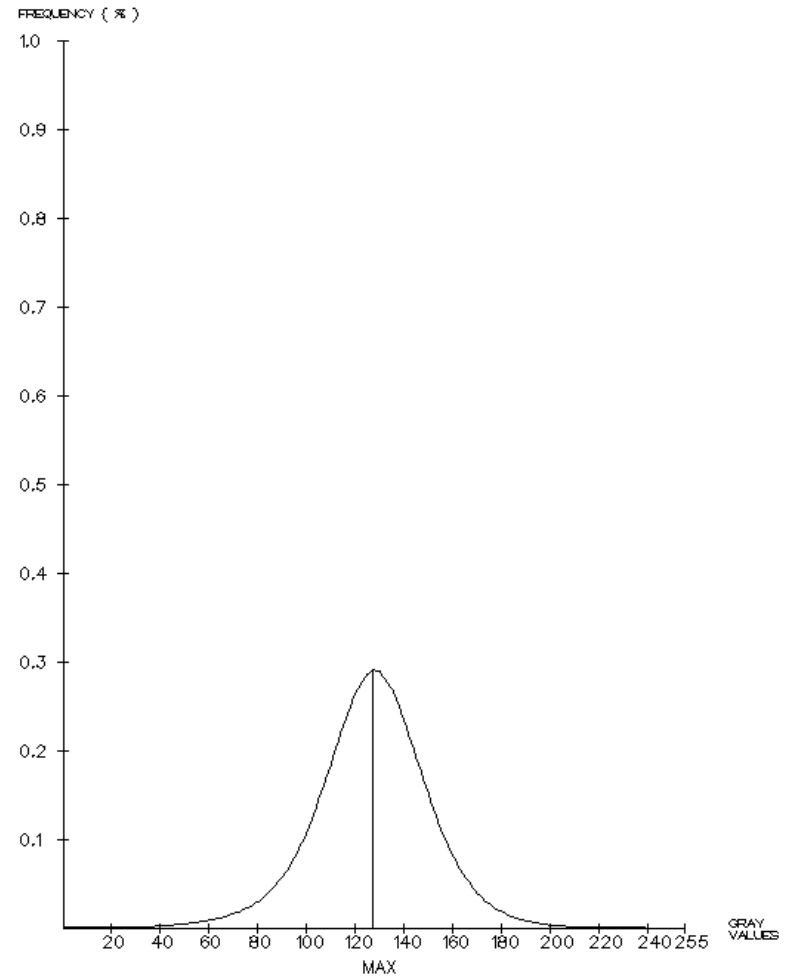
Fore channel

CHANNEL_6(FORE)
H-INTERVAL =1 GRAY VALUES
NUMBER OF PIXELS =24168096
SCALE FACTOR =5.017



Original image

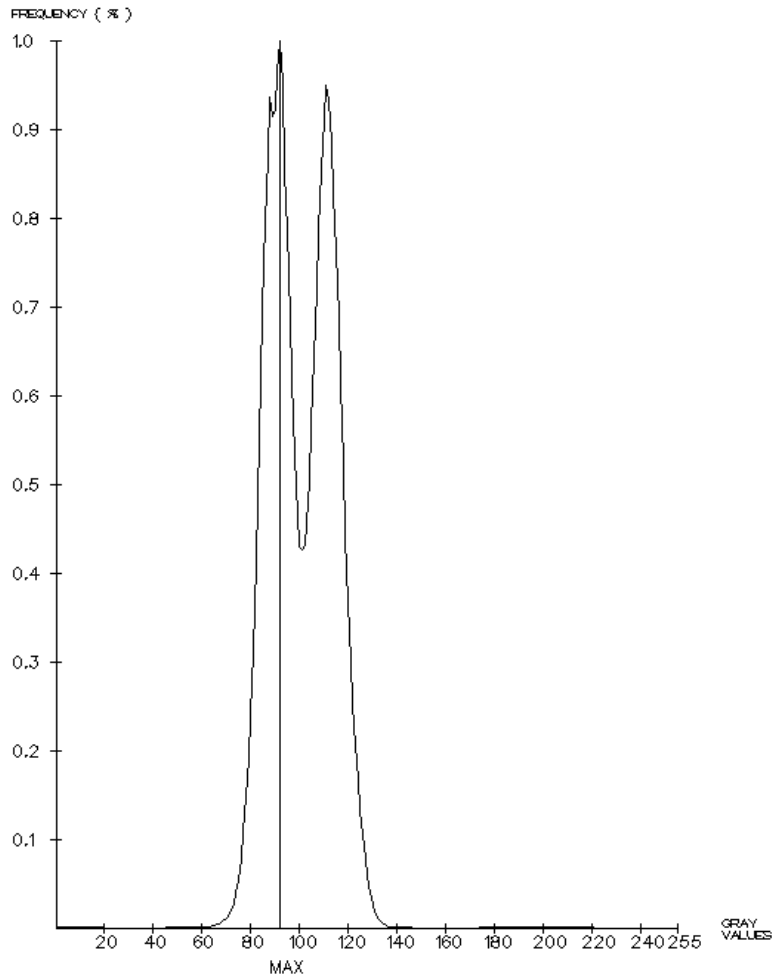
CHANNEL_6_PREPROCESSED
H-INTERVAL =1 GRAY VALUES
NUMBER OF PIXELS =24168096
SCALE FACTOR =5.017



After preprocessing

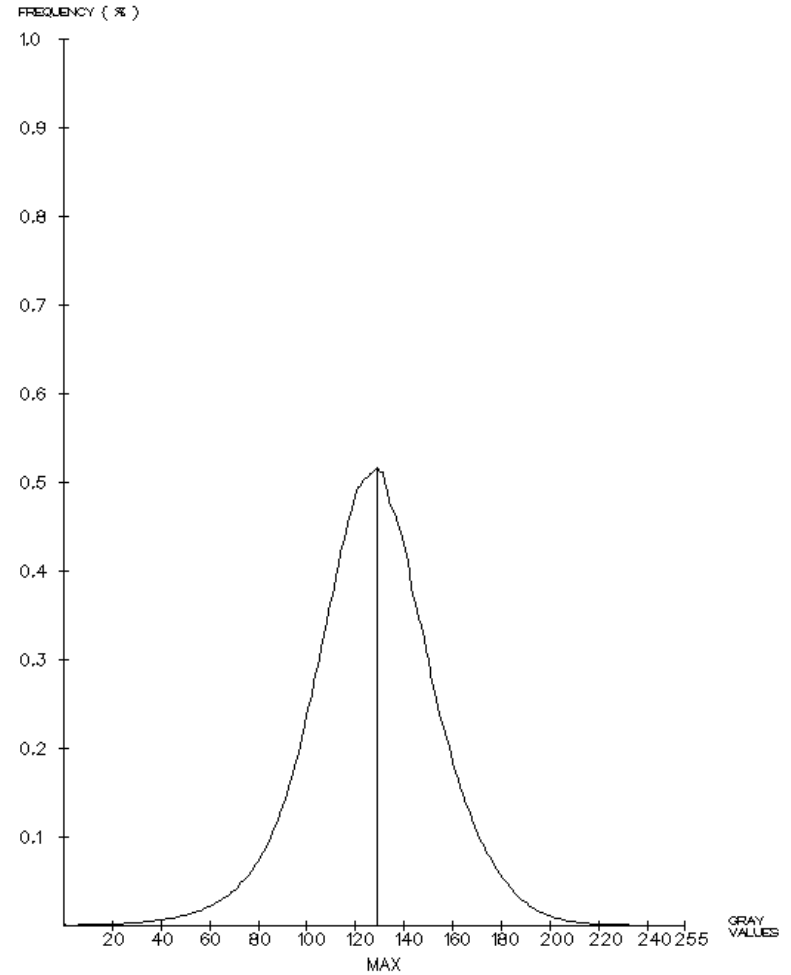
Nadir channel

MOMS_NADIR_5A_ORIGINAL
H-INTERVAL =1 GRAY VALUES
NUMBER OF PIXELS =67436784
SCALE FACTOR =29.941



Original image

MOMS_NADIR_5A_PREPROCESSED
H-INTERVAL =1 GRAY VALUES
NUMBER OF PIXELS =67436784
SCALE FACTOR =29.941



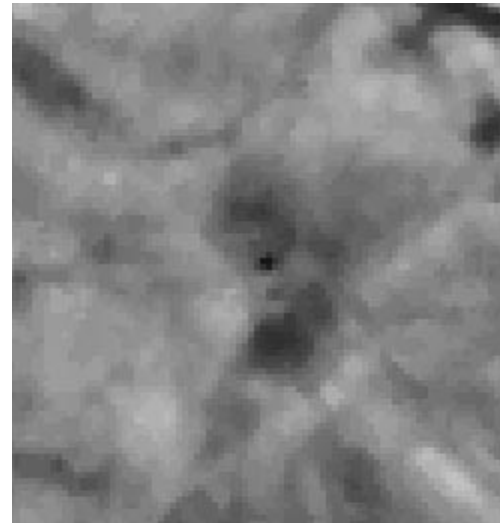
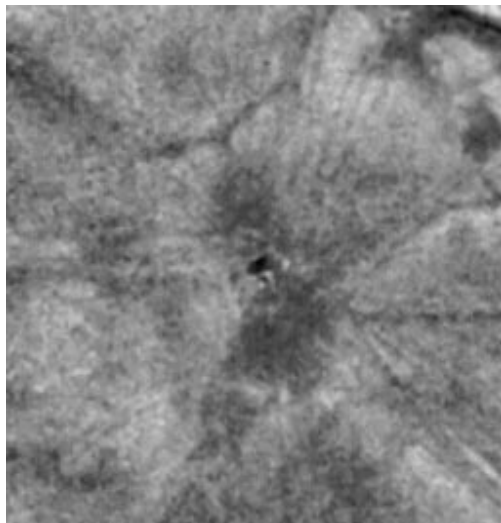
After preprocessing

Control Points



Well defined

Control point definition in the nadir (left) and fore (right) preprocessed images



Poorly defined

Bundle Adjustment Software

- *Kratky's* geometric sensor model
- Extended bundle adjustment for point determination and reconstruction of the exterior orientation (stereo and single images)
- Strict sensor modelling, elliptic orbit
- Sensor types: pushbroom and oscillating scanners, e.g.
SPOT, Landsat 5 TM, JERS-1 OPS, MOMS-02
- Unknown parameters per image:
6 exterior, 2 interior, 3 linear or 6 quadratic attitude rates
- Minimal number of required GCPs: 4 - 6, suggested 10

Point Positioning Accuracy

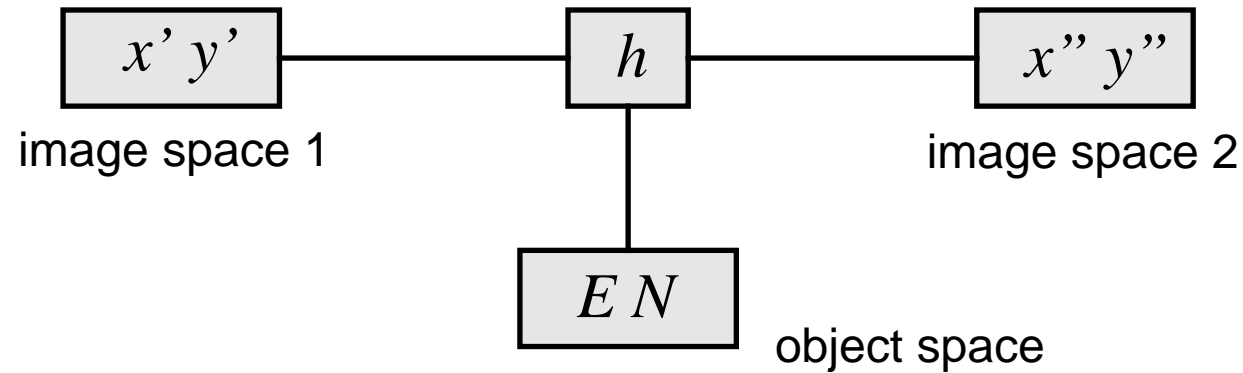
- Combination: Fore-aft
- Point measurement manually and by least-squares matching
Refinement of pixel coordinates from residuals of bundle
- Linear and quadratic attitude rates

Model	GCP	CHP	σ_0 [μm]	RMSE of CHPs [m]		
				μ_x	μ_y	μ_z
Q	20	45	3.6	6.2	6.4	6.7
Q	10	55	2.9	6.7	5.9	7.4
Q	6	59	2.3	7.4	10.7	7.9

Summary of Point Positioning Accuracy

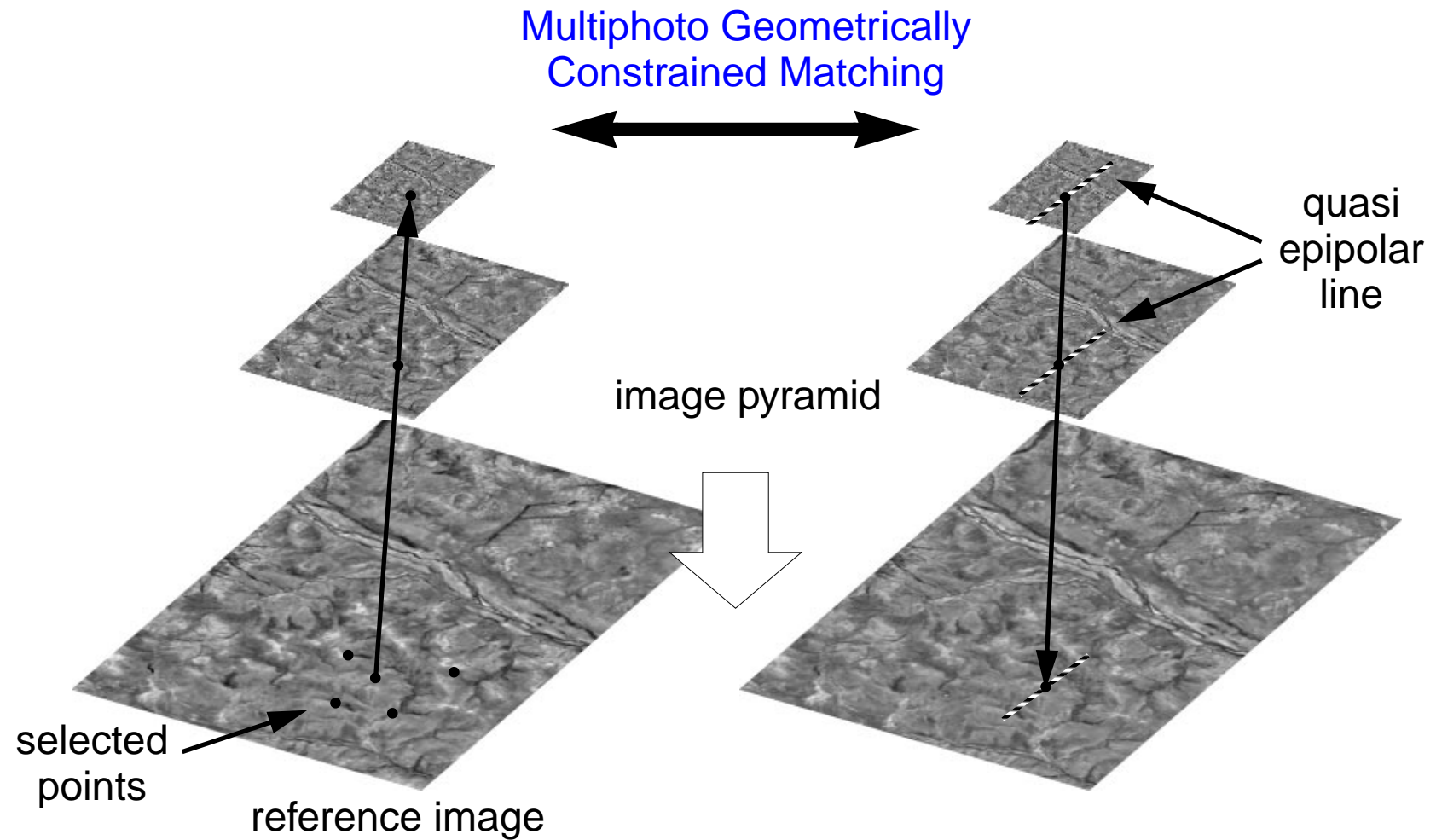
- Linear attitude rates 40% worse than quadratic
- 10 GCPs suffice
- With 6 GCPs solution sensitive to GCP selection
- Image point measurement with matching vs. manual
 - at least as accurate
 - faster

Fast Polynomial Mapping Functions



- Polynomial of $3^\circ - 4^\circ$ with 11 - 16 terms
- Height ...independent parameter connecting the three 2D spaces
- Much faster than rigorous transformations
- Almost equally accurate (difference < 0.1 pixel)

Automatic DTM Generation

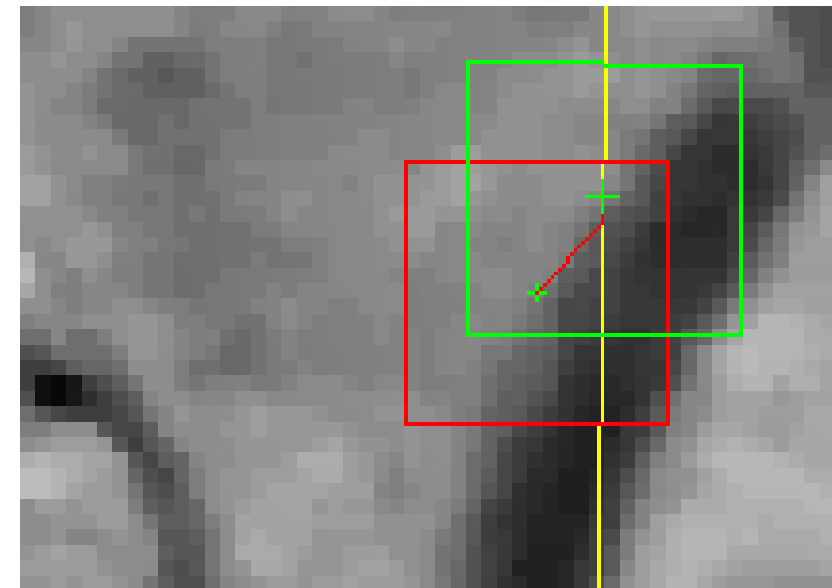
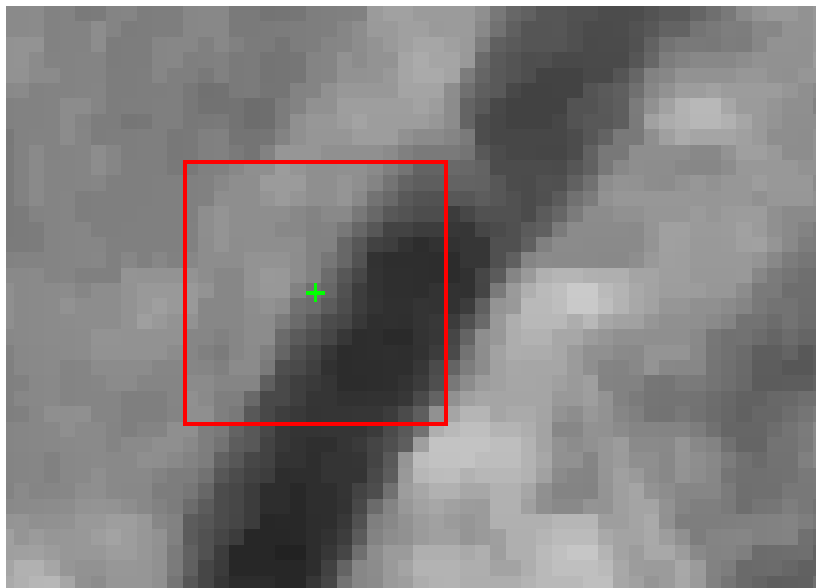
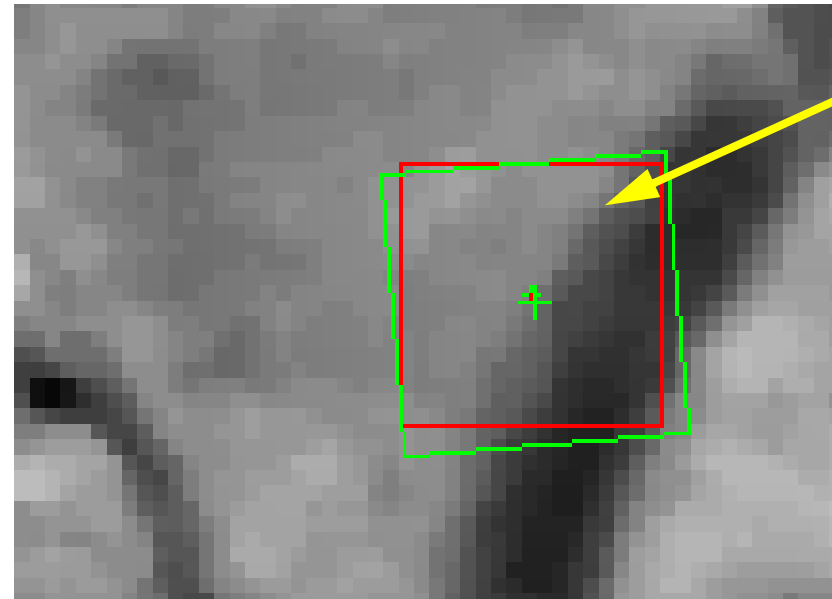
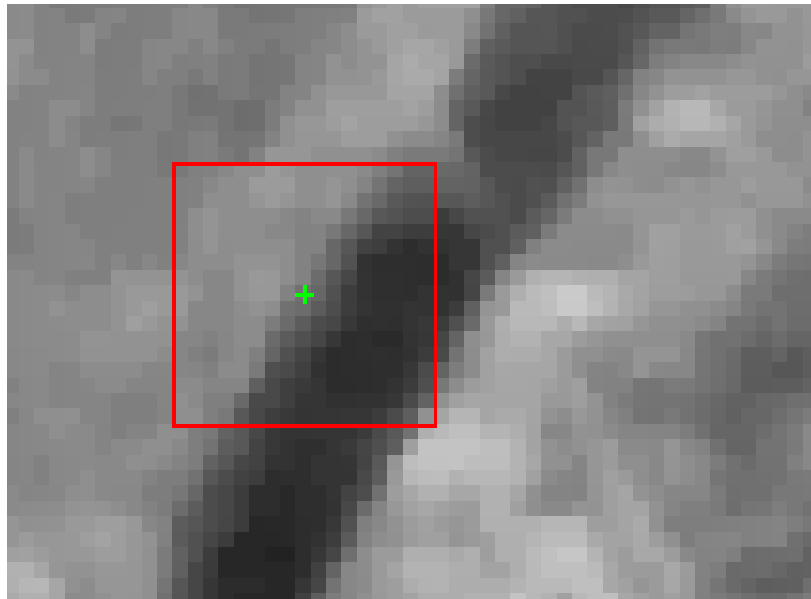


Constrained Least-Squares Matching

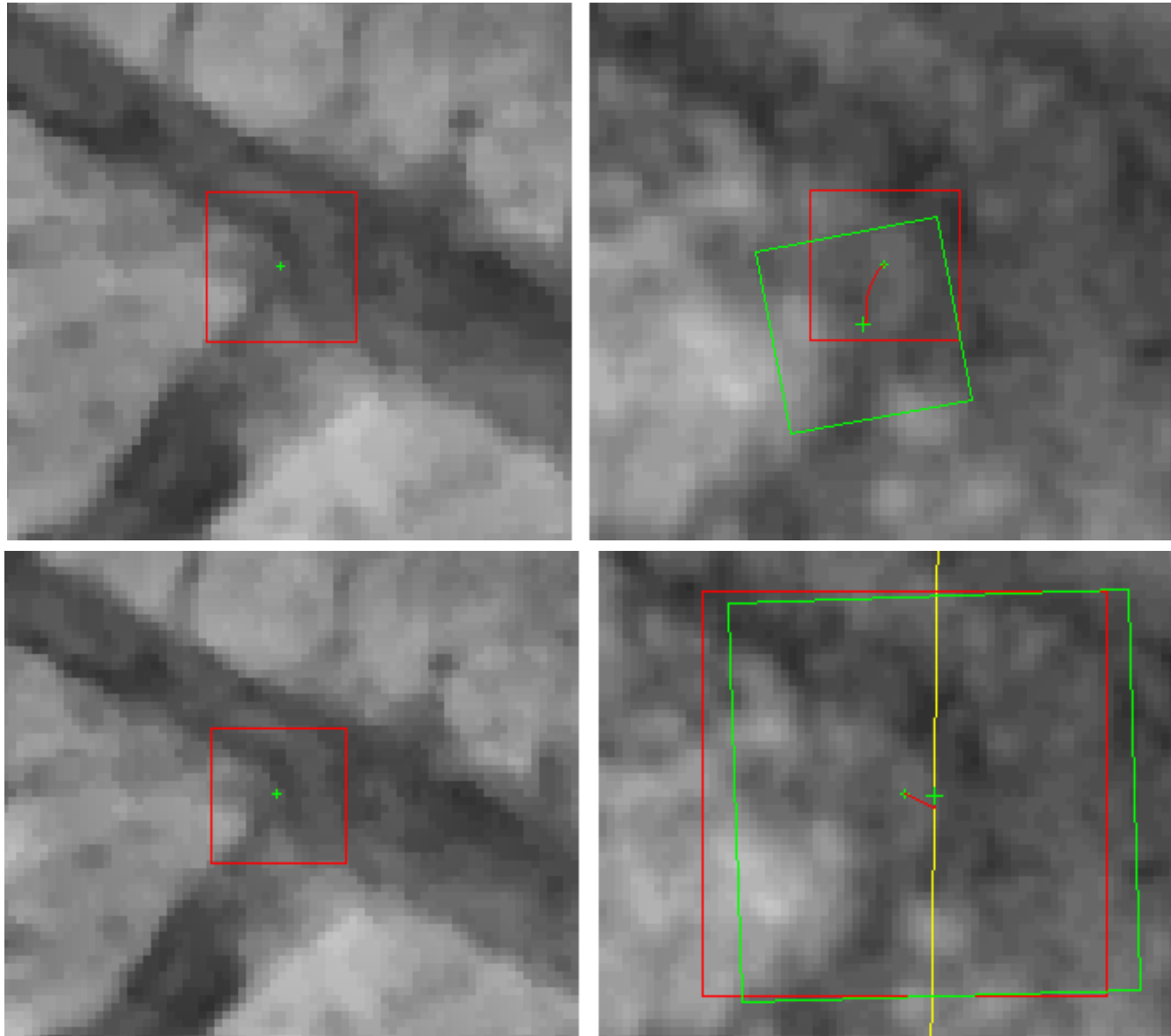
- Matching edge points, not in epipolar line direction
- Reduced errors due to multiple solutions, radiometric differences, noise etc.
- Higher success rate and reliability
- Any scale and rotation difference can be accommodated, e.g. fore and nadir
- Any number of images simultaneously matched (not implemented yet for MOMS)

Matching Parameters

- Fore and aft, 12 x 20 km area
- Two tests: 10,000 and 18,000 match points
- Patch size 17 x 17 pixels ... 230 x 230 m -> smoothing
- Conformal geometric transformation
- 4 pyramid levels



Matching along edges: without (top) and with (bottom) constraints



Matching fore (left) and nadir (right). Top: no constraints, scale approx. = 1.
Bottom: with constraints, scale approx. = 3

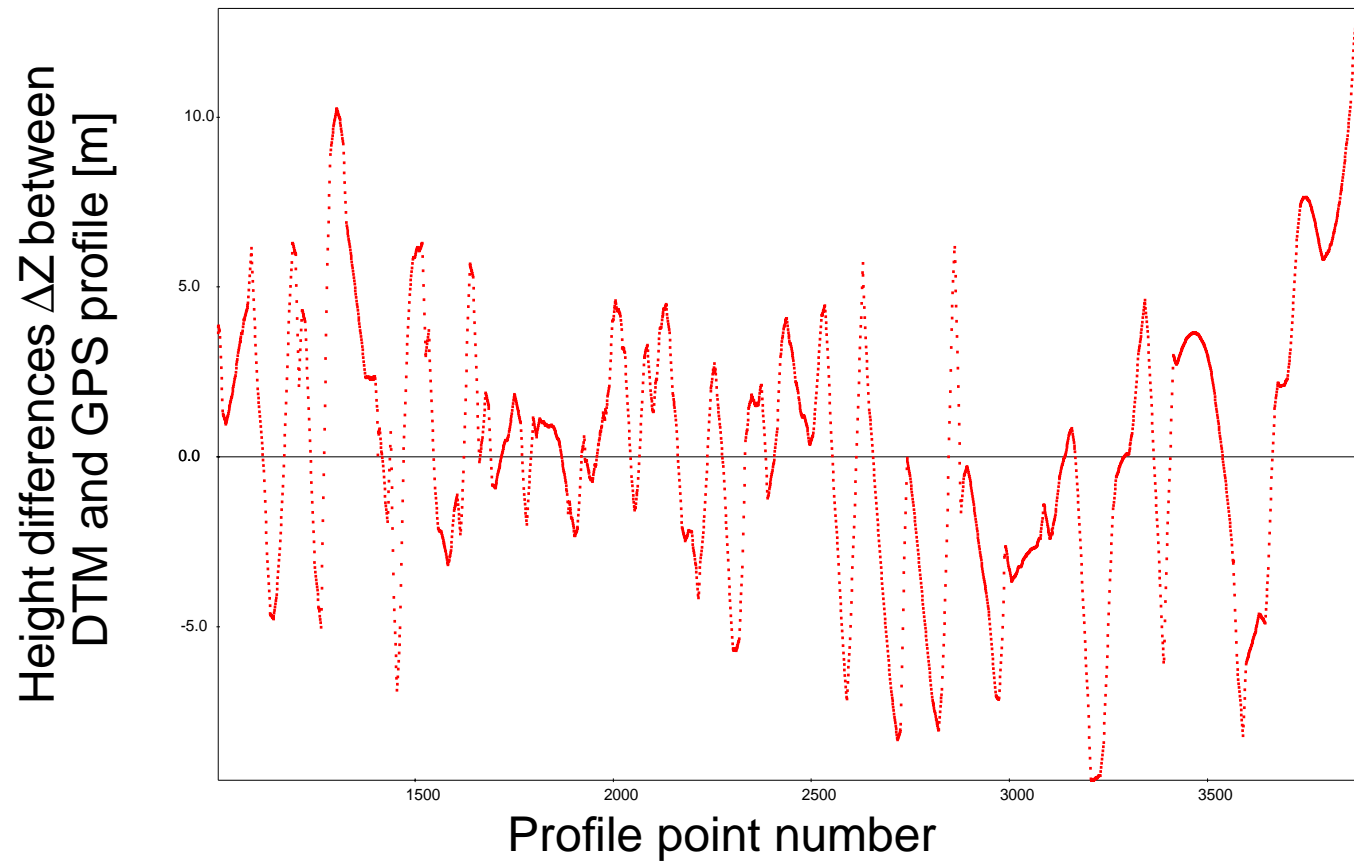
- Automatic detection and deletion of blunders
 - > 2.5% and 5.8% of points rejected in the two matchings
- Flat and open terrain, some creeks
- Very little radiometric differences
 - > huge advantage of along-track stereo



Radiometric differences:
Different water reflection

DTM Accuracy

Bilinear interpolation of 2,900 GPS values in 40 m regular DTM derived from matching



Statistics of ΔZ :

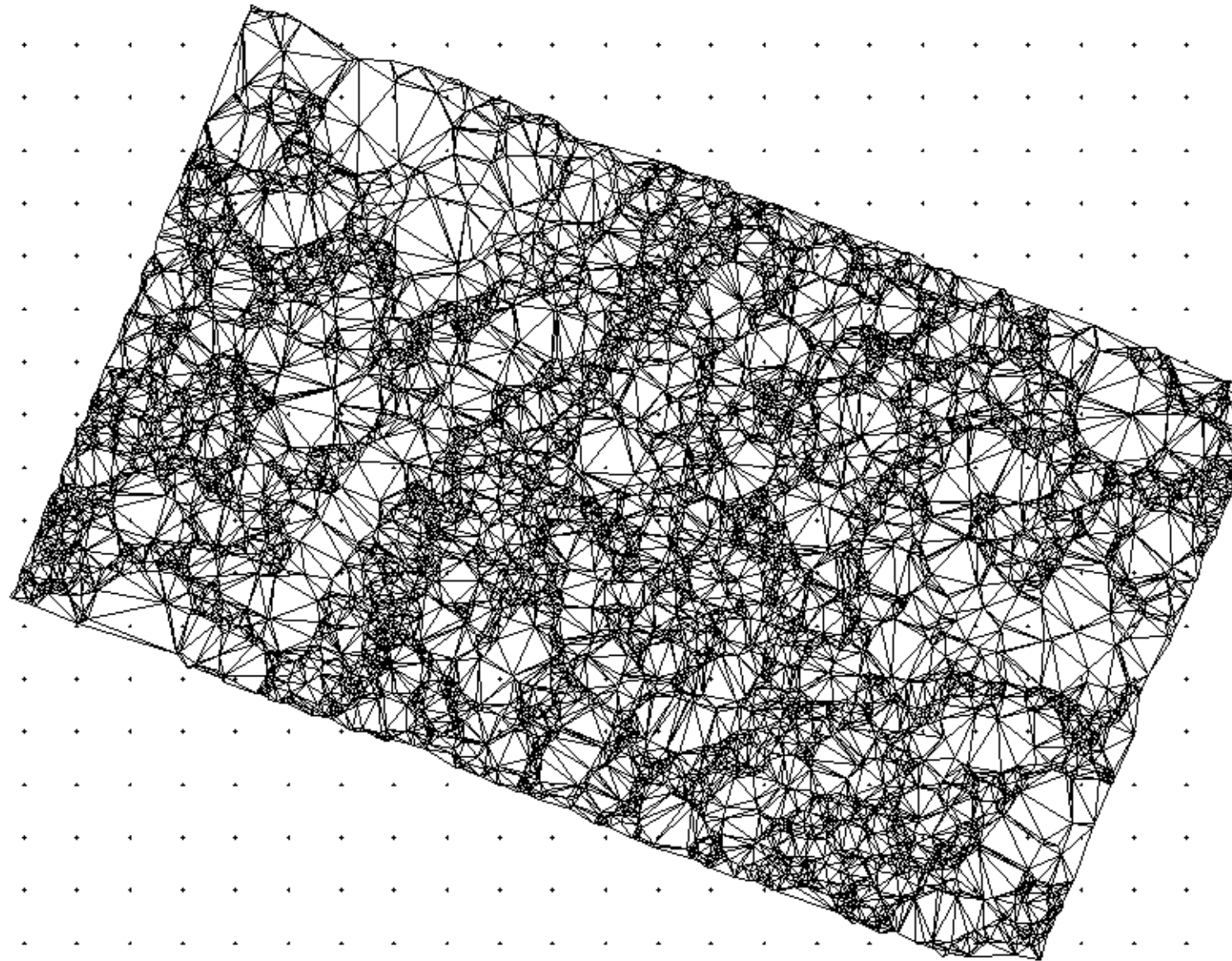
ΔZ_{mean} = 0.6 m

RMSE ΔZ = 4.2 m

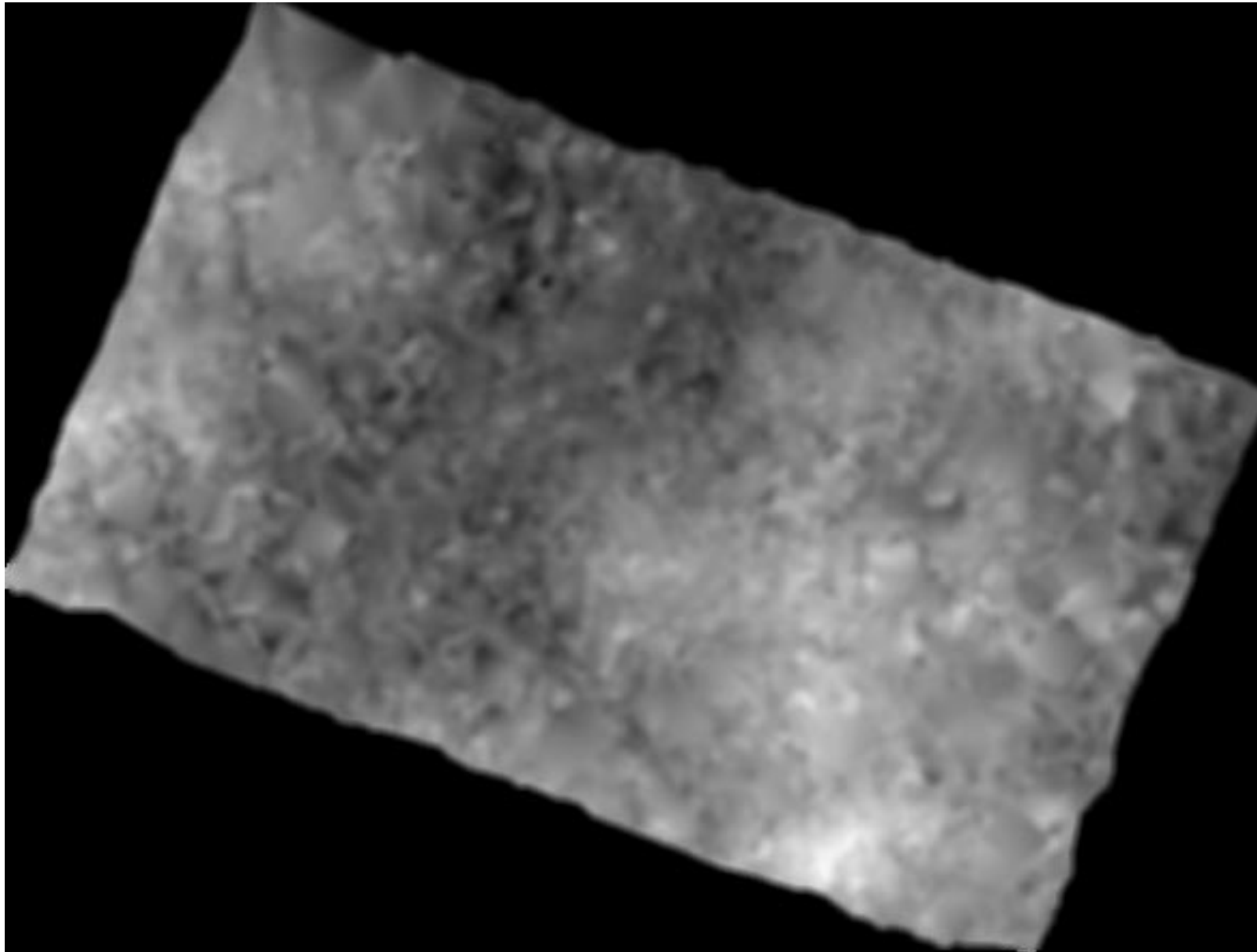
ΔZ_{max} = 13.2 m

Errors > 8.5 m due to:

- smoothing of discontinuities
- weak texture



Triangular meshes of 10,000 match points.

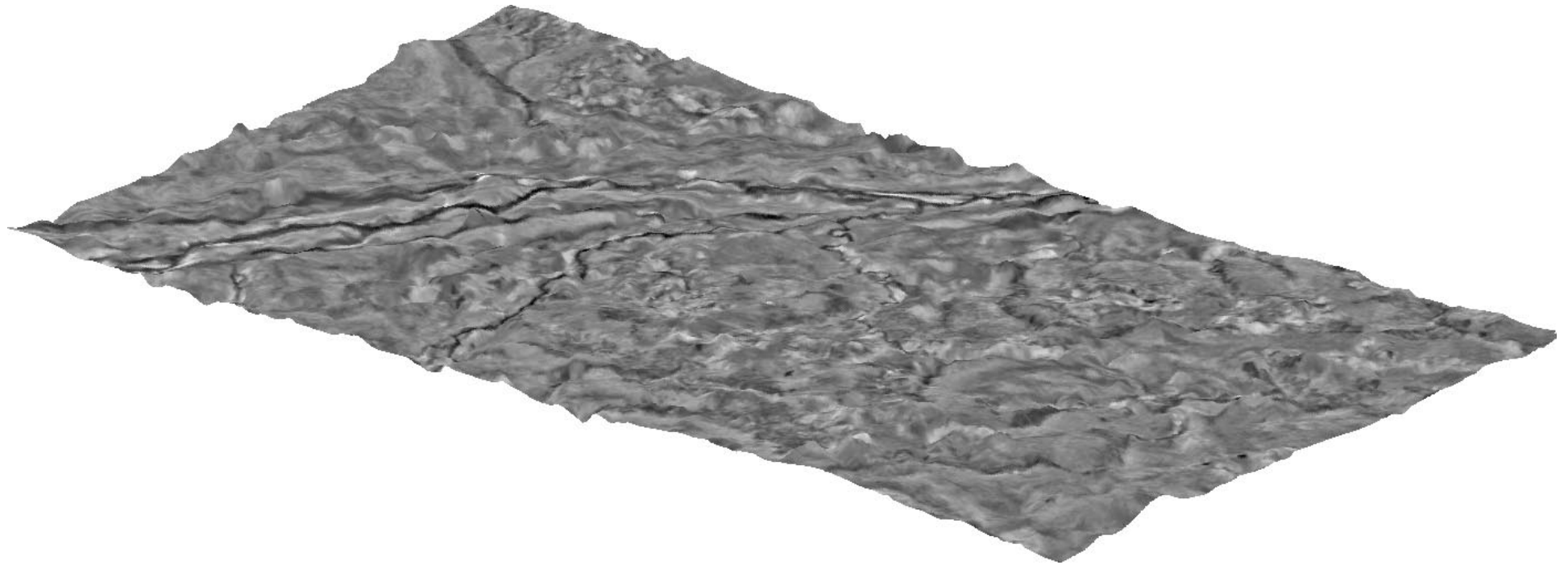


DTM derived from 18,000 match points and displayed as grey level image

Orthoimage generation

- Using DTM and PMFs to derive orthoimages
- Accuracy (related also to DTM accuracy)
 - from four GCPs: RMSE 5 - 6 m in planimetry and height
 - from parallaxes between orthoimages of fore and aft channel:
 - ideally should be identical
 - 50 points over whole area and at large radiometric differences
 - max. parallax 0.6 pixel (8 m), mainly at creeks
- 3.5 min. CPU time for fore or aft channel (SUN Sparcstation 20)

3D Parallel View



Top left part of the fore channel (12 km x 20 km). Orthoimage draped over the DTM
(height exaggeration factor 8)

Conclusions

- *Kratky's* model:
 - mathematically strict, modelling of calibration errors
 - operationally simple, flexible (various sensors)
 - quadratic rates, 10 GCPs, point measurement by matching
- PMFs:
 - fast and accurate
 - DTM and orthoimage generation
- Results (fore-aft channel):
 - Point positioning accuracy: in X, Y, Z: 6 - 7 m
 - DTM accuracy: RMSE 4.2 m, max. 13.2 m
 - Orthoimage: ca. 0.5 pixel accuracy, fast generation
 - No systematic errors in sensor model

Future Work

- Problems of this test:
 - poor: image quality, GCP definition, calibration
 - limited data set, flat and open terrain, no reference DTM
- Further tests with MOMS-PRIRODA using
 - good GCPs and reference DTM
 - different terrain types (slope, cover)
- Use of nadir channel in the investigations
 - expectations for improved planimetric accuracy