

MULTI-TEMPORAL ANALYSIS ON THE AREAS OF THE EARTHQUAKE IN CENTRAL ITALY - AN IMAGE BASED APPROACH IN PESCARA DEL TRONTO



OUTLINE

- A. TEAM DIRECT-VVFF SAPR
- B. MULTI-TEMPORAL ANALYSIS
- C. TEAM DIRECT IN PESCARA DEL TRONTO
- D. CONCLUSION AND FUTURE PROSPECTIVES



TEAM DIRECT – VVF SAPR group



DIRECT (DIlsaster RECovery Team) of Politecnico di Torino is a team composed by researchers, professors and students of architecture and engineering, which the goal of achieving and maintaining an education in advanced technologies of 3D Metric Survey and Remote Sensing using UAVs and innovative techniques. DIRECT works on all phases of Disaster Management (DM), with the analysis of environmental vulnerability and the immediate response to emergencies in post-disaster relief, with the goal to actively contribute to the protection of the territory, the architectural patrimony, the archaeological heritage, and in case of environmental emergencies.



MULTI-TEMPORAL ANALYSIS

The possibility of documenting the evolution of the urban space evolution is an important area of research and study.



12/2000



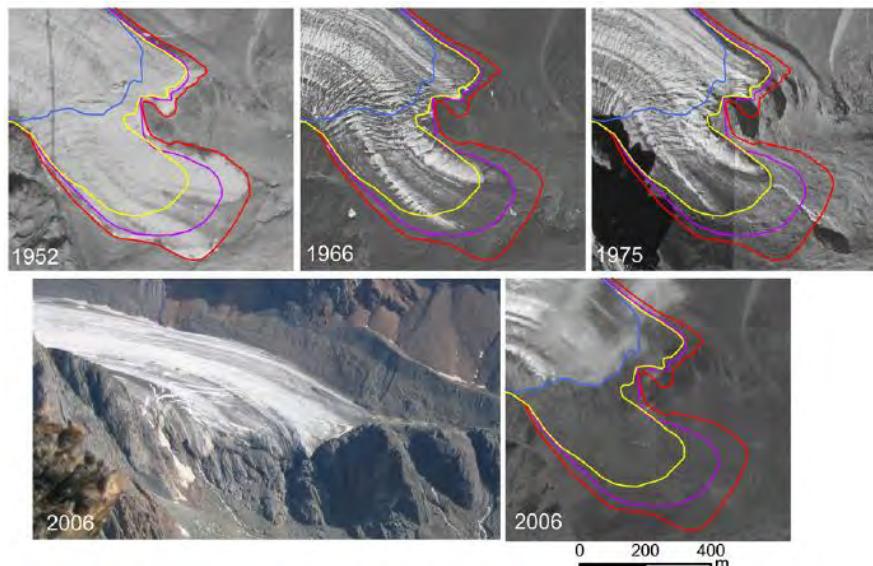
02/2005



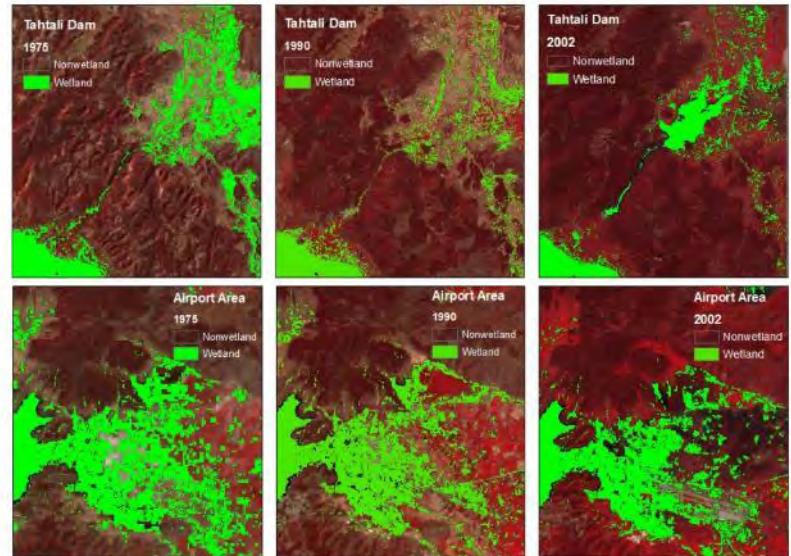
05/2016

Palm Jebel Ali, Dubai. Fonte: Google Earth.

MULTI-TEMPORAL ANALYSIS



Siberian Altai Mountains
Surazakov et al., 2007



Global Wetland-II Project
Hüttich et al., 2011

MULTI-TEMPORAL ANALYSIS

In case of natural hazard different strategy need to be used for understand the events: real time analysis with ad hoc sensor, (landslide, CH under risk etc), in other case a day weekly or month analysis could be ok.



09/16

12/16

02/2017

S.Agostino Church in Amatrice (RI).

PESCARA DEL TRONTO ACTIVITIES

- DIRECT TEAM of Politecnico di Torino in cooperation with the SAPR team of Vigili del Fuoco and the GEER team works together in three different missions on the field in order to perform high resolution metric surveys.
- Multi-sensor documentation of urban areas thanks to 3D *image-based* e *range-based* multi-temporal analysis
- Terrestrial sensor integration (*close-range photogrammetry*, LiDAR SLAM based, topographic measurements using total station and GPS/GNSS), UAV aerial acquisitions (fixed wings and multi-rotor).
- Test sites: Pescia, Pescara del Tronto, Cittareale, Accumoli, Norcia, Castelluccio, Amatrice, etc. In the present paper the activities and results on Pescara del Tronto will be presented and analyzed.



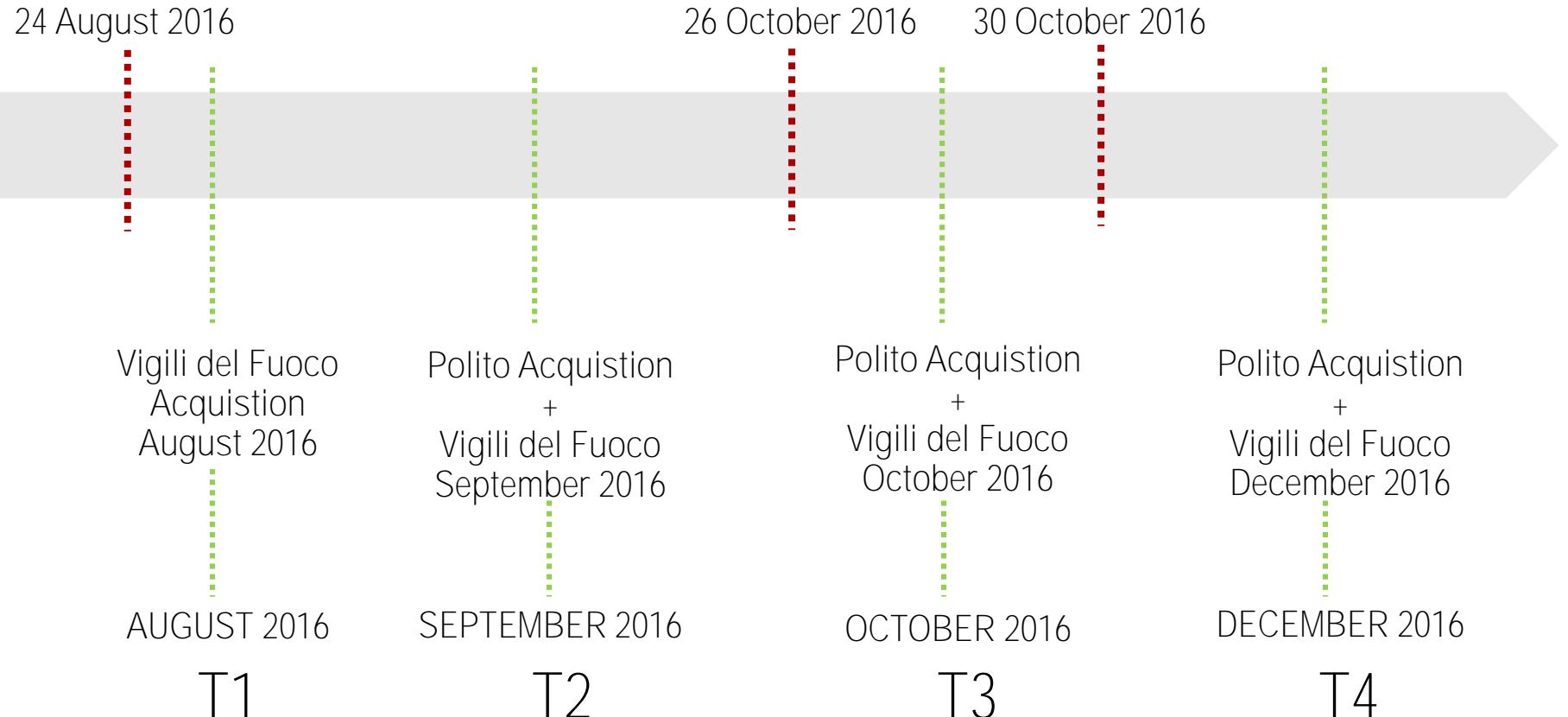
Some on the field activities

PESCARA DEL TRONTO ACTIVITIES



Pescara del Tronto between August and December 2016

EVENTS AND ACQUISITION TIMELINE



- I. ACQUISITIONS ACTIVITIES
- II. PROPOSED WORKFLOW
- III. DATA ANALYSIS AND VALIDATION



MULTI-TEMPORAL ANALYSIS ON THE AREAS OF THE EARTHQUAKE IN CENTRAL ITALY - AN IMAGE BASED APPROACH
IN PESCARA DEL TRONTO

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A
B
C
D

ACQUISITIONS ACTIVITIES

TEMPO	UAV ACQUISITIONS					GSD	GCPs	
	Operatore	Piattaforma	N° im.	Flight Elev	Area	cm/px	N°	Quality
1	August	Vigili del fuoco	eBee Sensfly	138	150m	0.6 km ²	6.3	-
2	September	Politecnico di Torino	eBee Sensfly	125	150m	0.38 km ²	5.7	23 (+)
3	October	Politecnico di Torino	eBee Sensfly	345	150m	0.67 km ²	7.3	38 (+)
4	December	Vigili del fuoco	DJI Inspire	409	100m	0.34 km ²	2.9	17 (-)

Overview of the 2016 acquisitions activities



ACQUISITION ACTIVITIES

RPAS SYSTEMS

- **eBee™ Sensefly**
- DJI Inspire 1



ACQUISITION ACTIVITIES

RPAS SYSTEMS

PLATFORM

T1-T2-T3

- **eBee™ Sensefly**
- DJI Inspire 1

- Produced by sense fly and commercialized by Menci Software in Italy
- Fixed wing, very light platform perfect for emergency context
- Elevation up to 200m 20 min. of range camera mounted in the nadir position
- Other sensor available such as Multispectral NIR RE and Thermal
- ENAC certified as harmless (EBM-1539).



ACQUISITION ACTIVITIES

RPAS SYSTEMS

CAMERA

- **eBee™ Sensefly**
 - RGB Camera Canon IXUS 127 HS16,1 MP (4608 x 3456) sensor CMOS 6,17 x 4,55 mm, weight of 135g.
- DJI Inspire 1
 - RGB Camera Canon Power Shot **S110™ 12,1 MP (4000 x 3000)** sensore CMOS 7.44 x 5.58 mm, weight of 172g.

T1

T2-T3



ACQUISITION ACTIVITIES

RPAS SYSTEMS

PLATFORM T4

- eBee™ Sensefly
 - DJI Inspire 1
- DJI Product (Dà-Jiāng Innovations Science and Technology Co., Ltd Technologies)
 - INSPIRE1, multirotor quadricopter
 - Weight of about 3kg with the camera (maximum weight at take-off 3,5 kg) flight range of 20 minuts.
 - Oblique and nadir images acquistion



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ACQUISITION ACTIVITIES

RPAS SYSTEMS

CAMERA

- **eBee™ Sensefly**
 - ZENMUSE X5 camera. CMOS Sensor focal lenght 15mm F/1.7-F/16, field of view 72 degree
- DJI Inspire 1



ACQUISITION ACTIVITIES

GEOREFERENTIATION

- GPS/GNSS in RTK mode
- Portable GNSS
- Georeferencing using GeoTag informations



A



B



B



C

A) Target positioning ; B) Survey operations ; C) Images GeoTagging

ACQUISITION ACTIVITIES

GEOREFERENTIATION

- GPS/GNSS in RTK mode



- Dual frequency Geomax Zenith 35
- GPS/GLONASS/GALILEO/BEIDOU
- Accuracy 5-10mm statico; 10-20mm RTK

ACQUISITION ACTIVITIES

GEOREFERENTIATION

- Portable GNSS

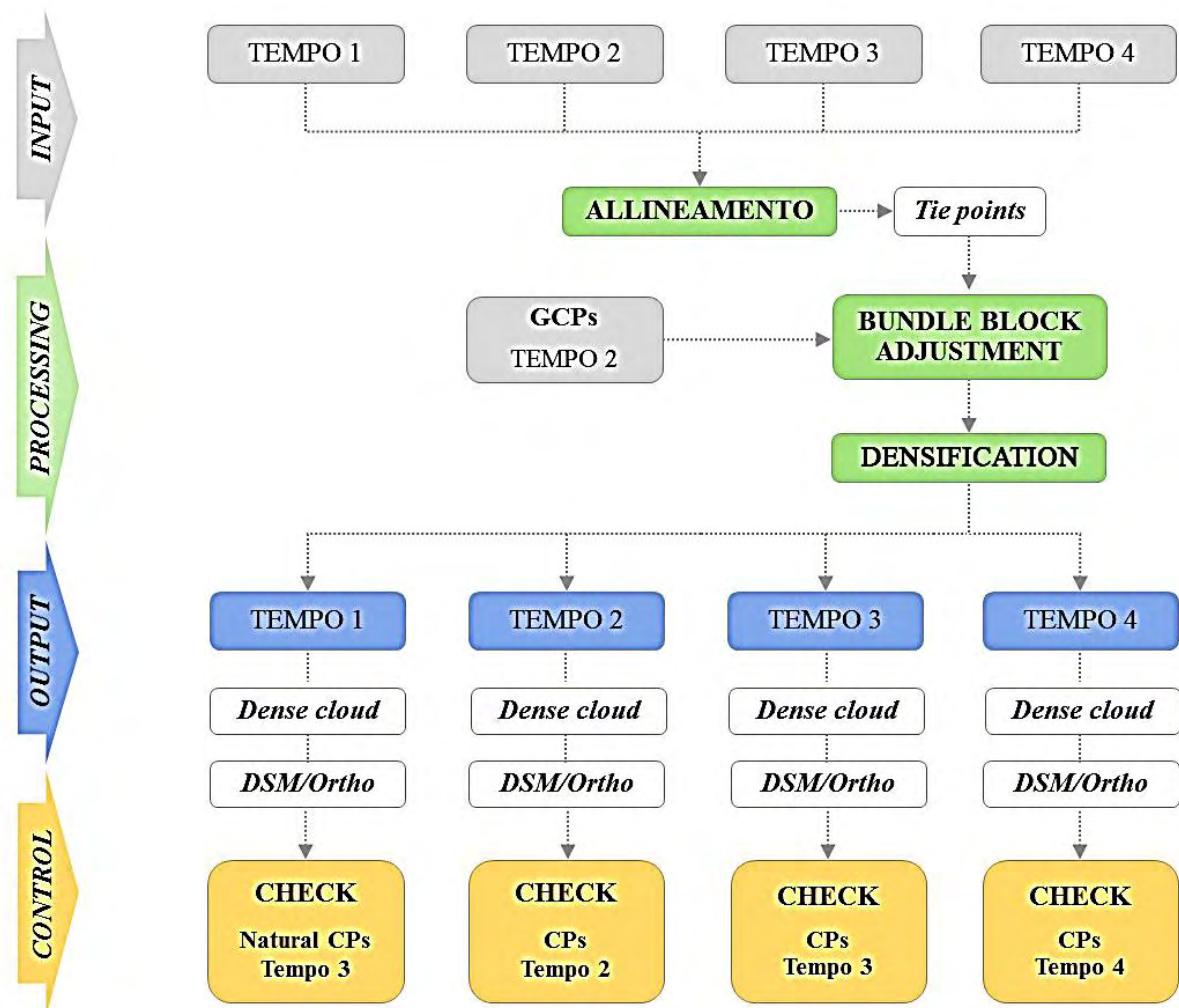


- Garmin GPSMAP® 64s
- GPS/GLONASS
- Accuracy 3-5m

WORKFLOW

Multi-temporal co-registration

The block co-registration has been followed using an ad-hoc workflow in order to testing a quickly procedure for improve the use of images for minimizing the empleyement of GCPs that are very time spending and dangerous operation in emergency areas.



WORKFLOW

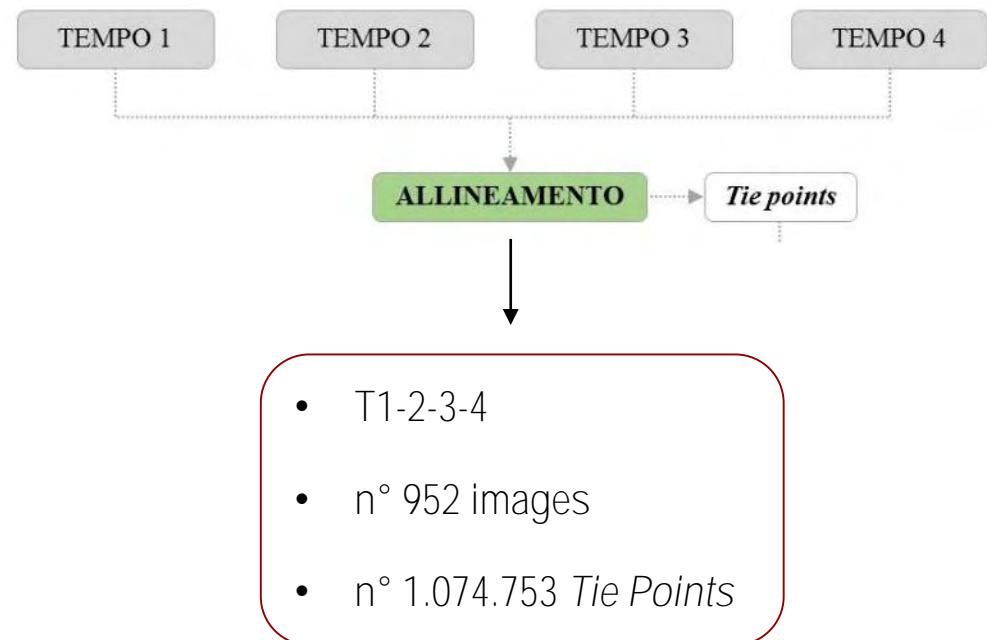
Multi-temporal co-registration

For the first step of the workflow all the images were oriented together.

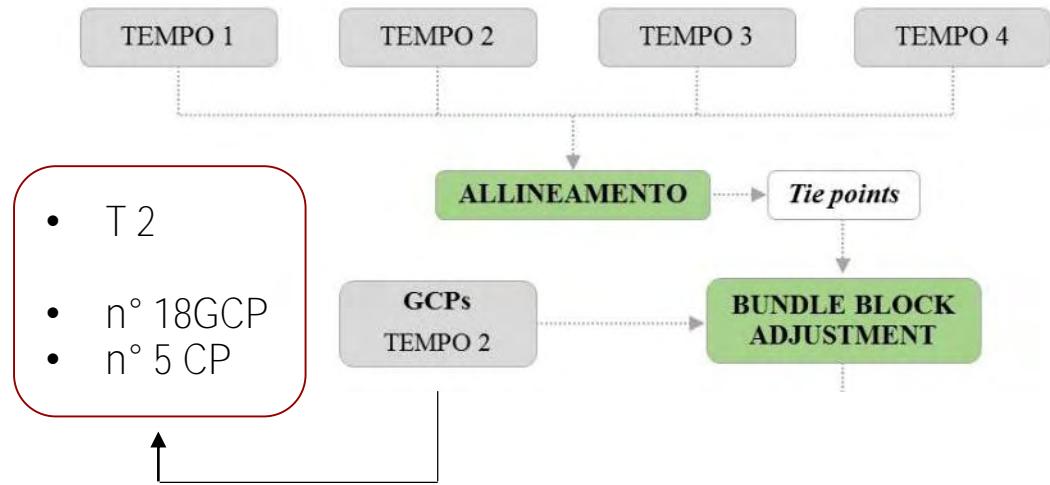
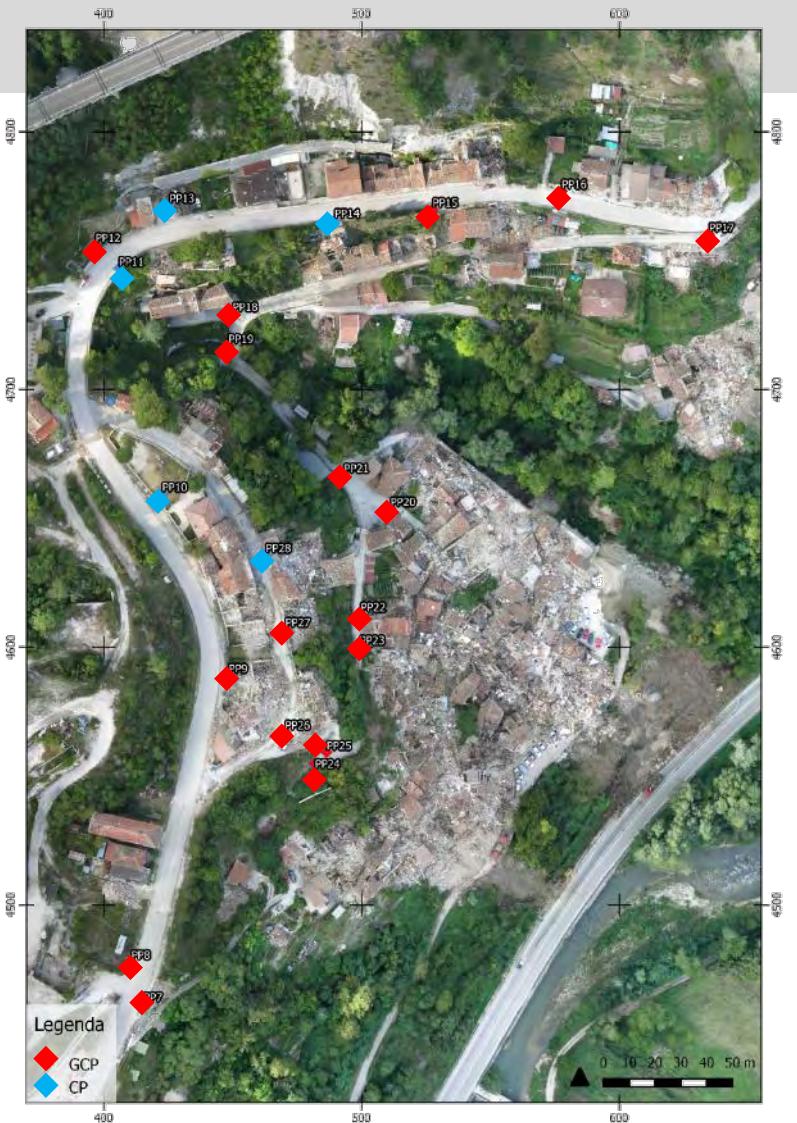
In this phase of the project the *image-matching* algorithms allow to extract a series of 2D *feature points* on the images the so called *Keypoints*, useful for the next bundle-block adjustment in order to define the internal and external orientation parameters.



WORKFLOW



Starting from the extracted Tie Points only a part were employed for the *Bundle Block Adjustment* that allow to estimate the position and attitude of the cameras during the acquistion. Only the blue points were effectevely used for the BBA since were recognized as common features in the differents set of images.



During the *Bundle Block Adjustment* only a single set of Ground control Points was used. The aim of the test was the evaluation of the *Point Cloud Densification* generated using the afore mentioned co-registration that allow to the image-matching algorithms to realize a complete cartographic product using different images (same area but different radiometric characteristic and objects according to the seismic events).

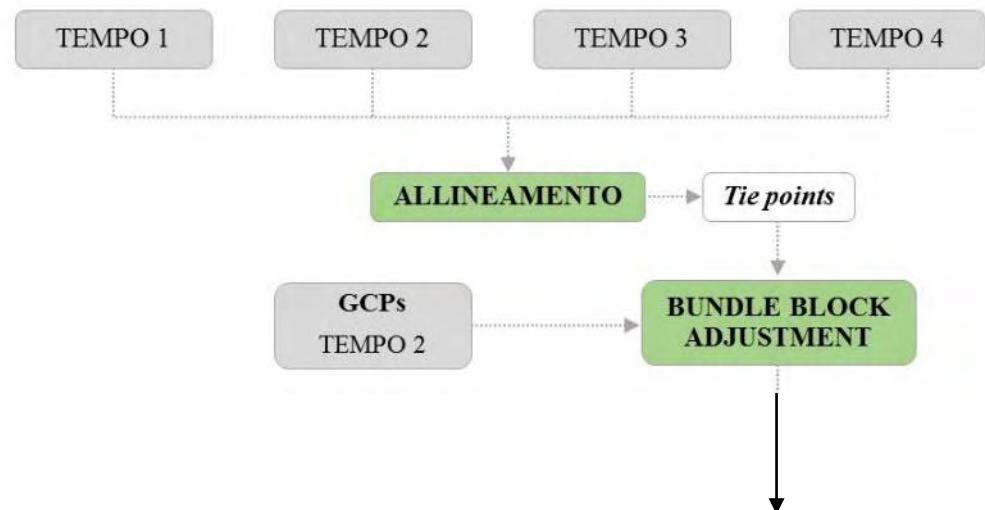
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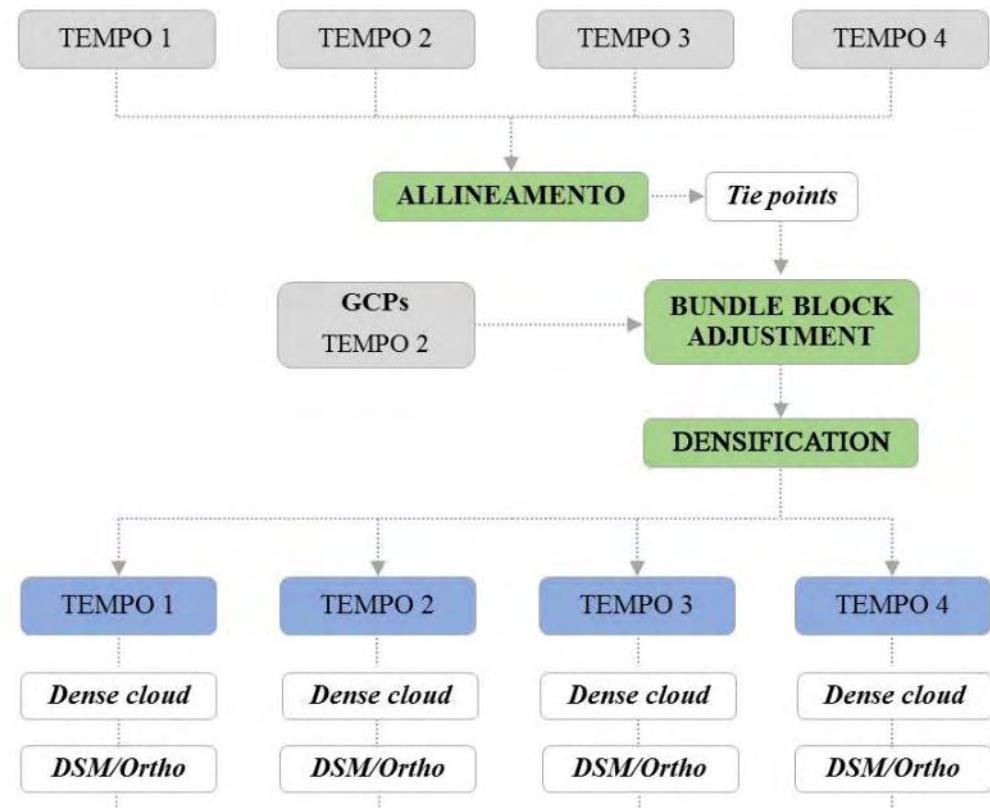
WORKFLOW



N° images (T1, T2, T3, T4)	N° Tie Points	n°18 GCPs, T2								n°5 CPs, T2							
		RMS (cm)				Mean (cm)				RMS (cm)				Mean (cm)			
		X	Y	Z	error	X	Y	Z	error	X	Y	Z	error	X	Y	Z	error
952	1.074.753	3.671	3.158	4.741	3.857	3.257	2.722	3.750	3.243	0.879	2.476	10.405	4.587	0.753	2.452	8.916	4.040

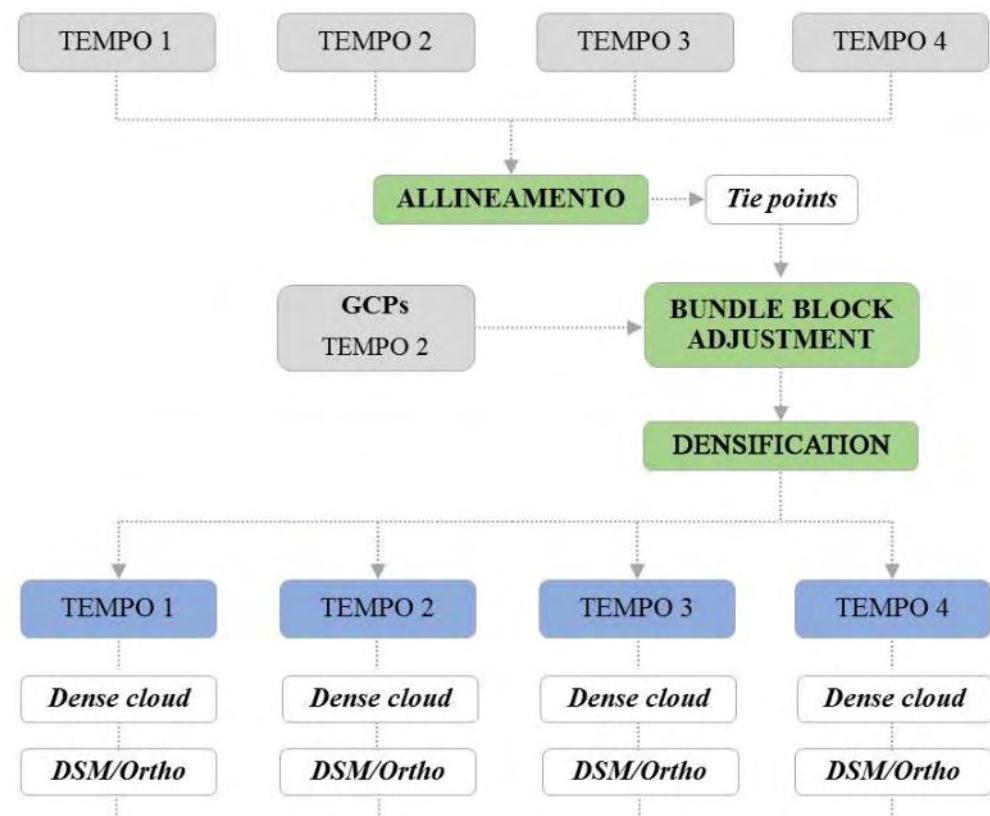
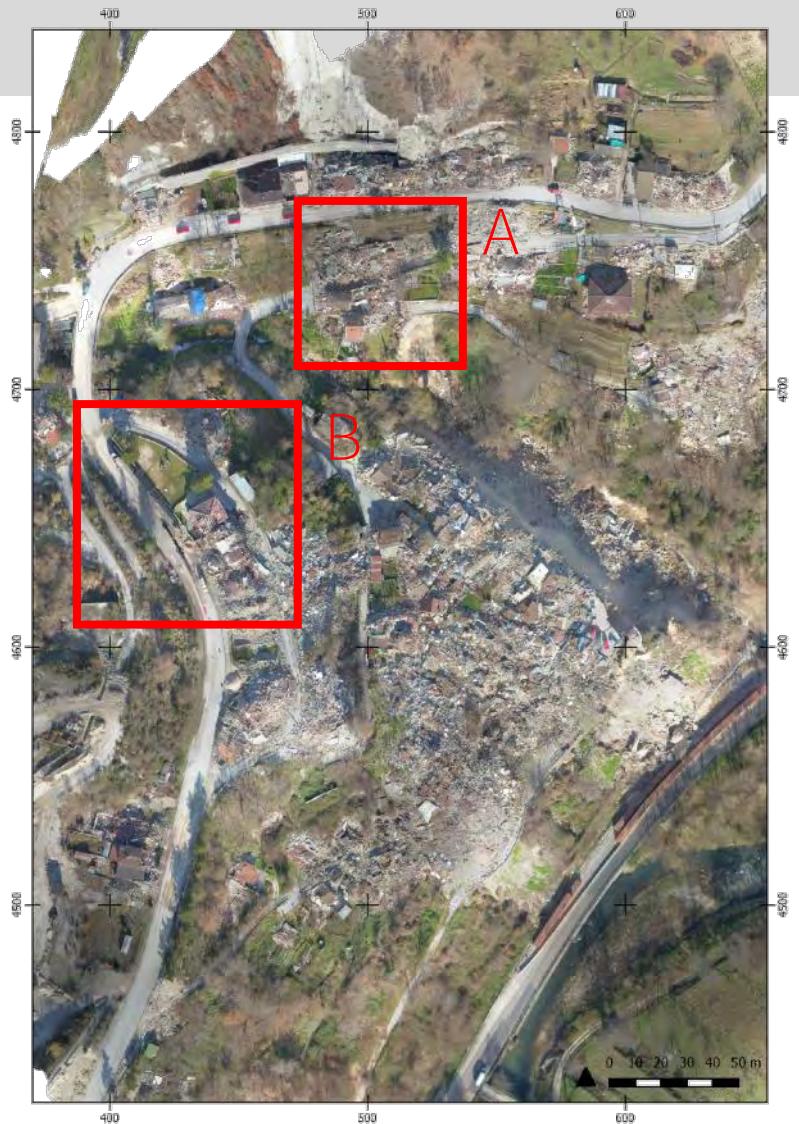
Accuracy of the Bundle Block Adjustment

WORKFLOW



For each time the DSM and orthophoto were achieved.





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A
AUGUST



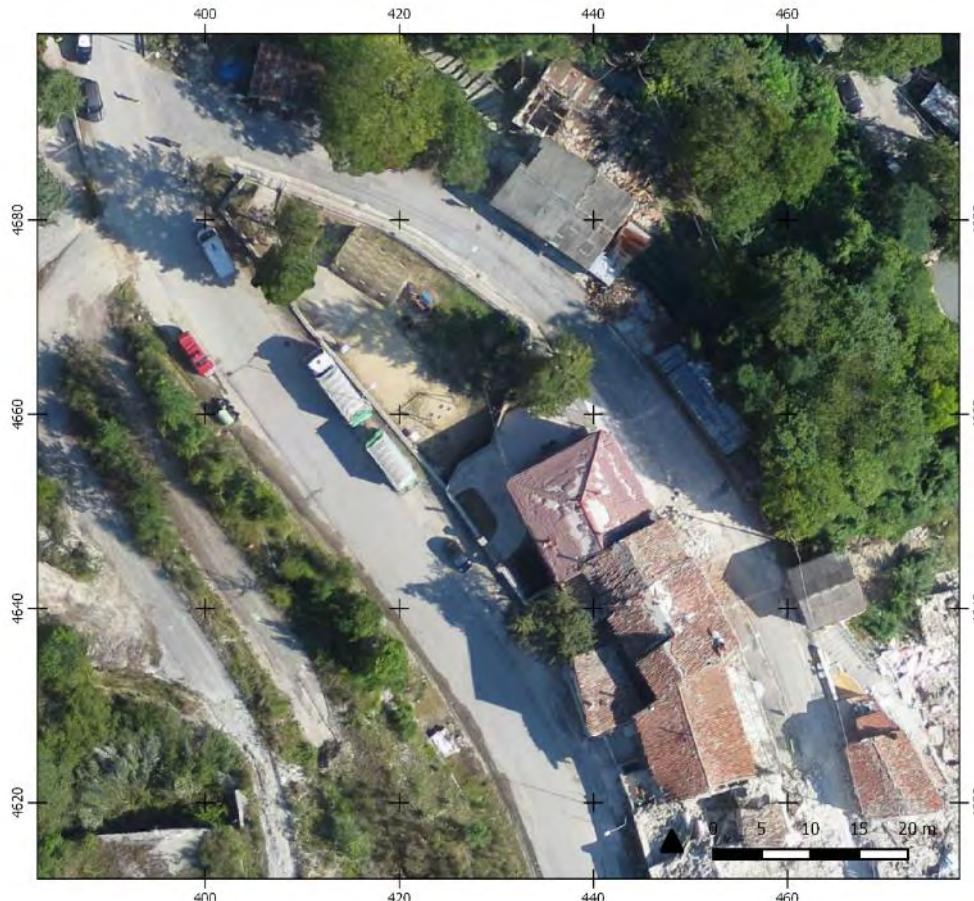
A
SEPTEMBER



A
OCTOBER



A
DECEMBER



B
AUGUST





B
SEPTEMBER





B
OCTOBER

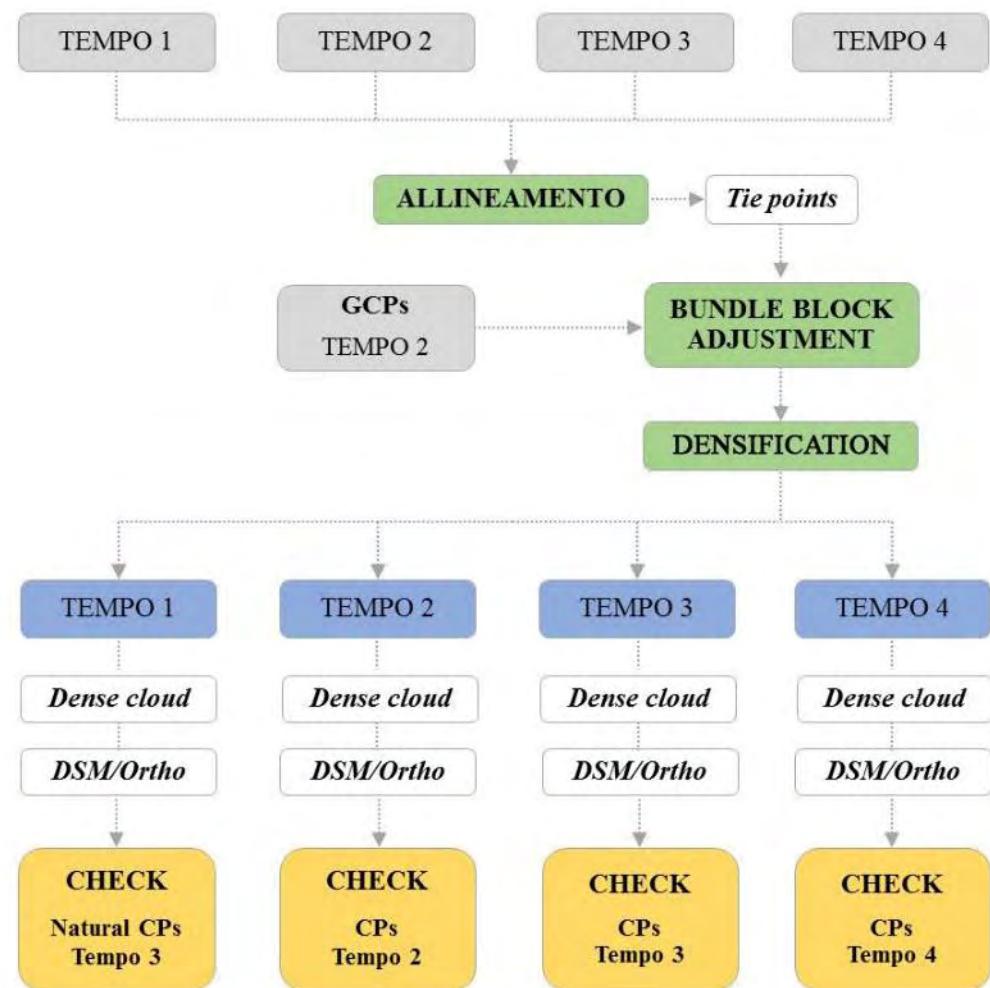
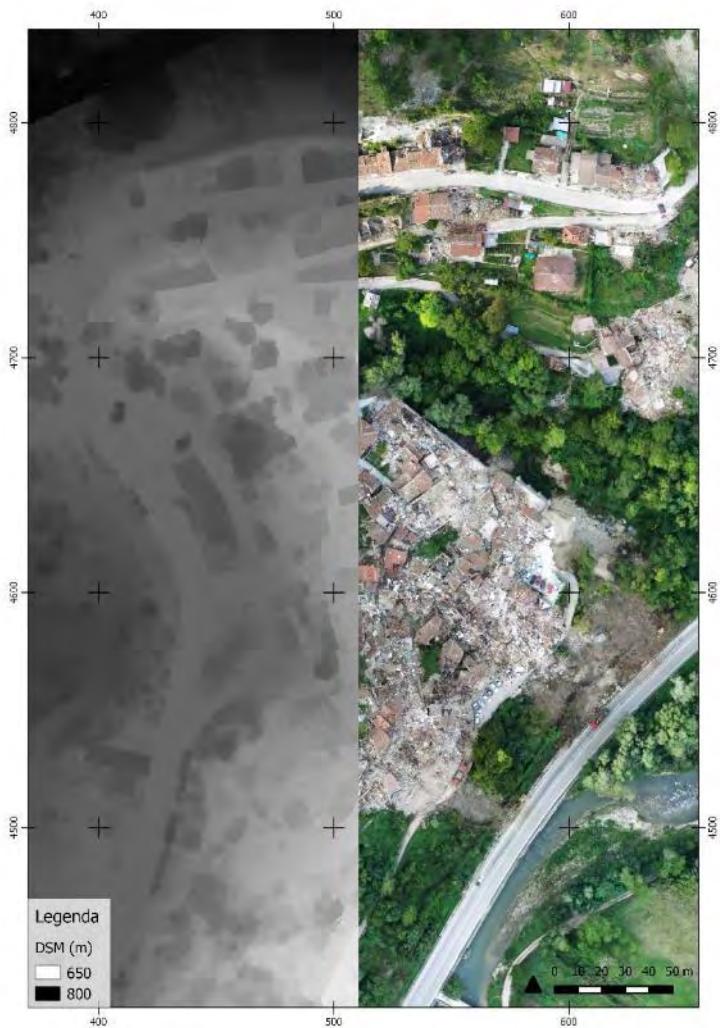




B
DECEMBER



WORKFLOW



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WORKFLOW

According to the results is possible to state that the realization of the 3D metrical products checked using a large number of CPs is suitable for a correct representation of the terrain and the object that are built on it.

DATASET	CHECK		RMS (cm)				MEAN (cm)				
	n° CPs	Dataset	X	Y	Z	error	X	Y	Z	error	
T1	August	12 (natural pt.)	T3	3.910	4.429	26.395	11.578	4.684	5.722	26.763	12.389
T3	October	31	T3	2.764	3.895	24.310	10.323	3.391	7.961	18.619	9.991
T4	December	11	T4	7.939	28.343	51.074	29.118	11.411	52.173	66.161	43.248

Accuracy on the different achieved products



DATA ANALYSIS AND VALIDATION

OCTOBER DATASET

For a more deeper analysis of the achieved photogrammetric products, two different startegies are reported in the following slides in order to suggest some improvements for data acquistion and processing during emergency operations.

The optimization of the image acquistion operation and geometry with a reduction of GCPs will be reported in order to evaluate possible different strategy despite to the traditional workflow used in photogrammetric acquisitions and data processing.

1. Acquistion

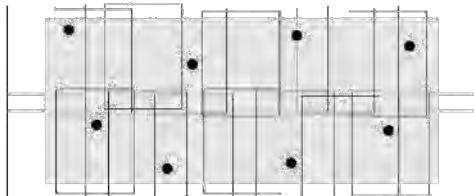
Image Acquisition
strategy

Number and GCPs
position

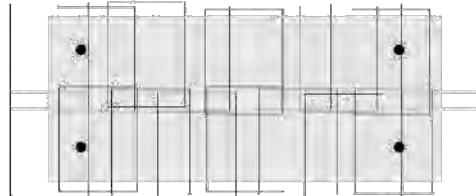
2. Gereferentation strategies

1 – ACQUISITION STRATEGY

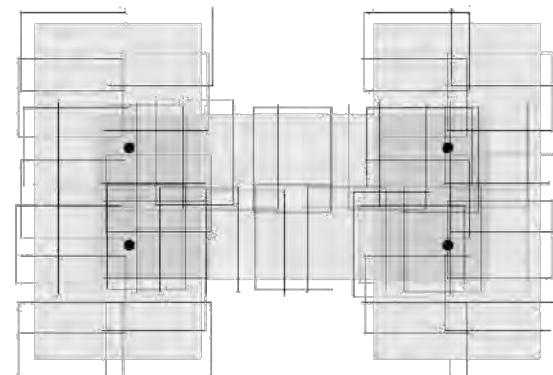
- (A) Single strip/large number of GCPs
- (B) Single strip/few GCPs
- (C) Multiple strips/few GCPs



(A)



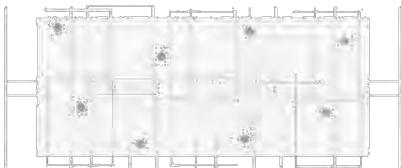
(B)



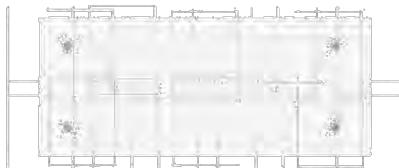
(C)

DATA ANALYSIS AND VALIDATION

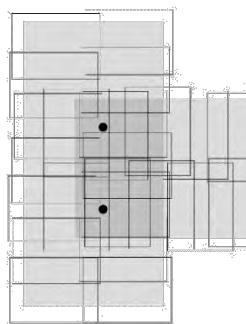
1-ACQUISITION
2-GEOREFERENTIATION



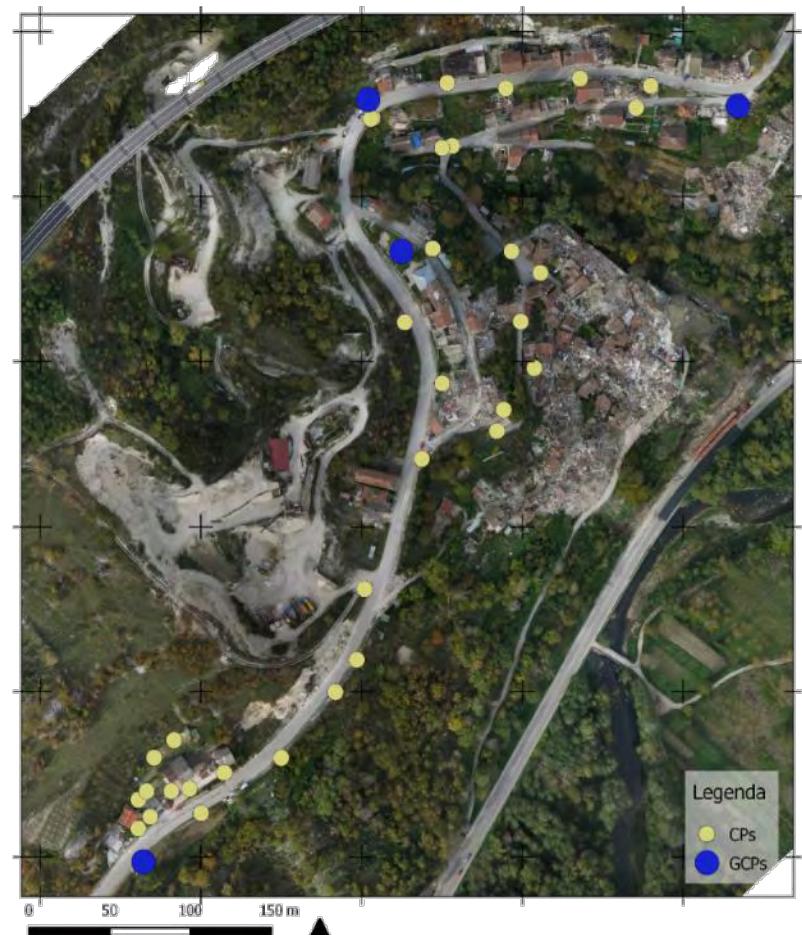
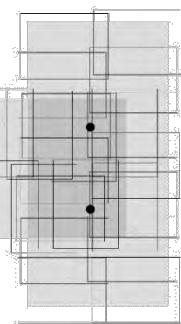
(A)



(B)

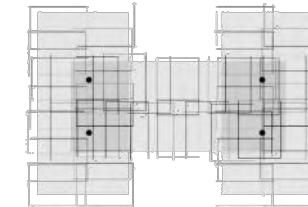
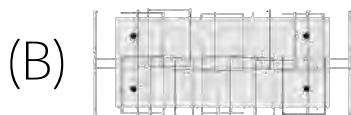
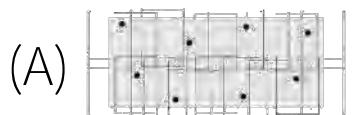


(C)



DATA ANALYSIS AND VALIDATION

1-ACQUISITION
2-GEOREFERENTIATION



n° images	n° GCPs	GCPs RMS (cm)				GCPs MEAN (cm)				
		X	Y	Z	error	X	Y	Z	error	
A	180	18	1.837	1.560	1.892	1.763	1.194	1.168	1.467	1.276
B	180	4	0.558	0.986	0.474	0.673	0.465	0.857	0.402	0.575
C	343	4	0.741	1.125	0.664	0.843	0.593	1.050	0.550	0.731

Results on GCPs for the three different followed strategy: A, B, C.

n° images	n° CPs	CPs RMS (cm)				CPs MEAN (cm)				
		X	Y	Z	error	X	Y	Z	error	
A	180	8	3.427	1.317	1.955	2.233	2.532	1.019	1.747	1.766
B	180	22	2.616	1.646	2.830	2.364	1.801	1.178	2.567	1.849
C	343	22	2.552	1.759	1.774	2.028	1.765	1.272	1.428	1.488

Results on CPs for the three different followed strategy: A, B, C.

2 - GEOREFERENTIATION STRATEGY

GPS/GNSS in RTK mode → GROUND-TRUTH (DSM/Ortofoto)

- Portable GNSS
- Georeferenatation using the image GeoTag



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A
B
C
D

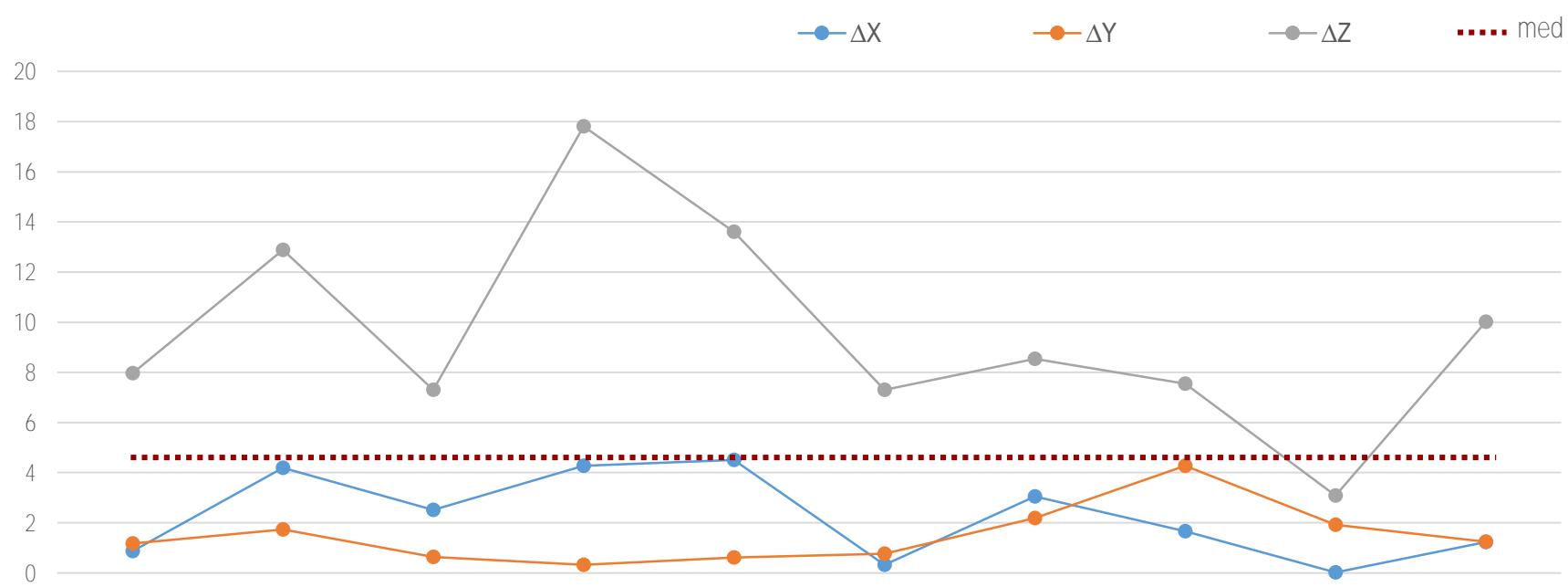
DATA ANALYSIS AND VALIDATION

1-ACQUISITION
2-GEOREFERENTIATION

Portable GNSS

COMPARISON
GEODETIC RTK VS portable GPS

	n°10 CPs			
	X	Y	Z	error
Mean (m)	2.264	1.488	9.608	4.453
RMS (m)	2.646	1.941	4.155	2.914



DATA ANALYSIS AND VALIDATION

1-ACQUISITION
2-GEOREFERENTIATION

Portable GNSS



Legenda

- Palmare GPS
- rtk GNSS

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1-ACQUISITION
2-GEOREFERENTIATION

Portable GNSS



Legenda

- Palmare GPS
- rtk GNSS



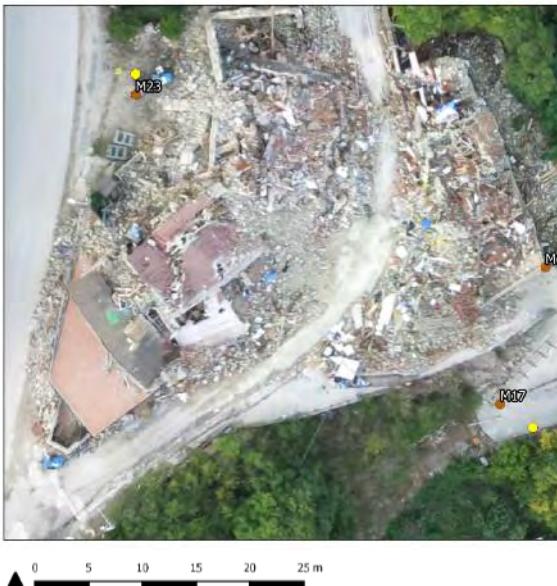
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Portable GNSS



Legenda

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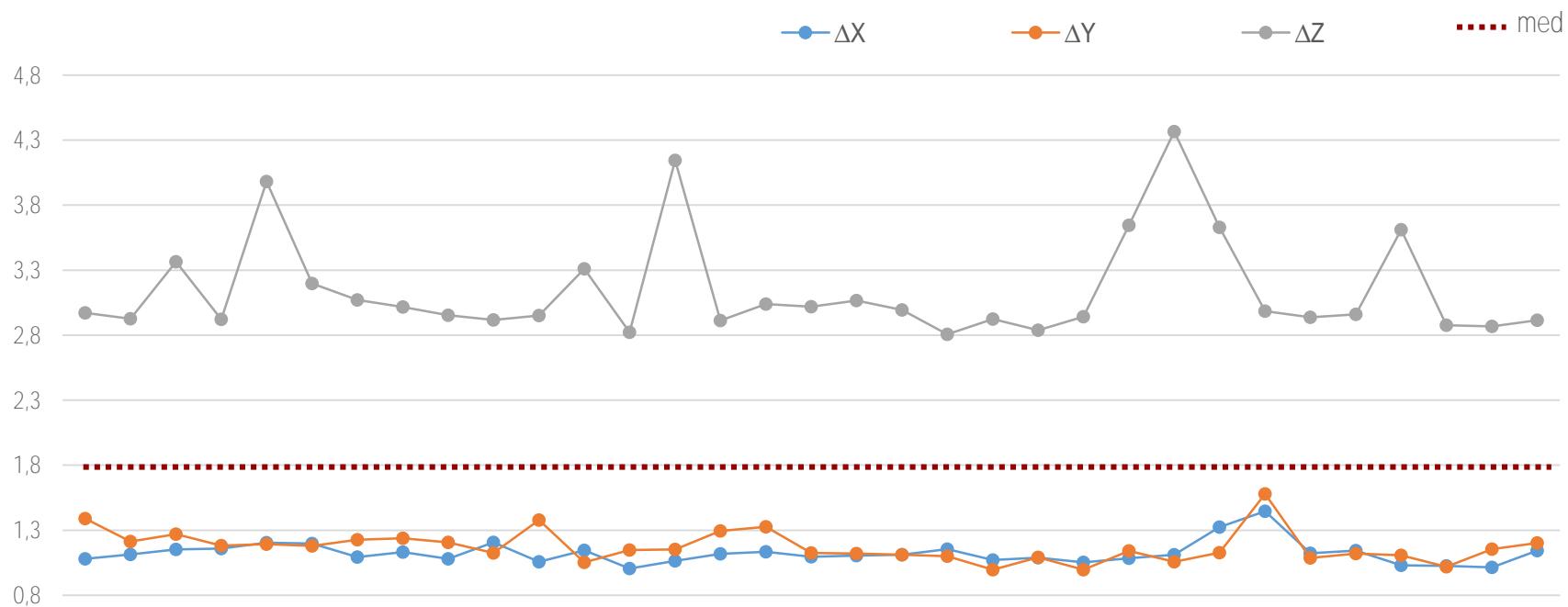
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DATA ANALYSIS AND VALIDATION

1-ACQUISITION
2-GEOREFERENTIATION

GeoTag

COMPARISON GEODETICRTK <u>VS</u> GeoTag	n°34 CPs			
	X	Y	Z	error
Mean (m)	1.124	1.173	3.148	1.815
RMS (m)	0.086	0.121	0.398	0.202



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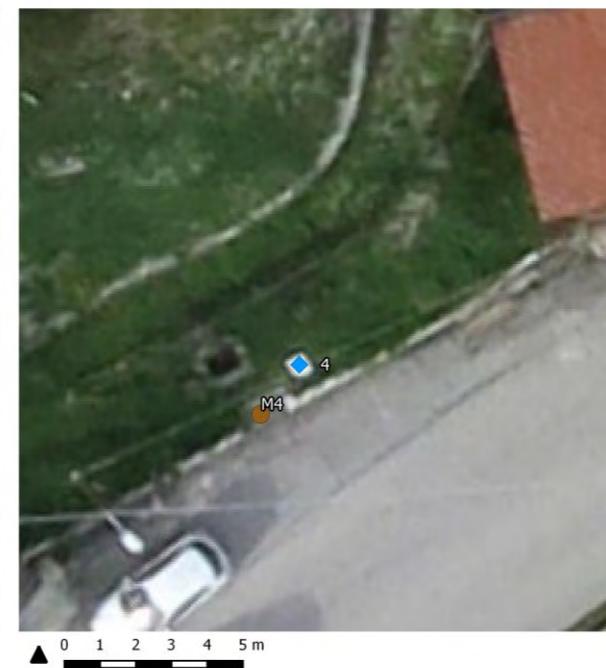
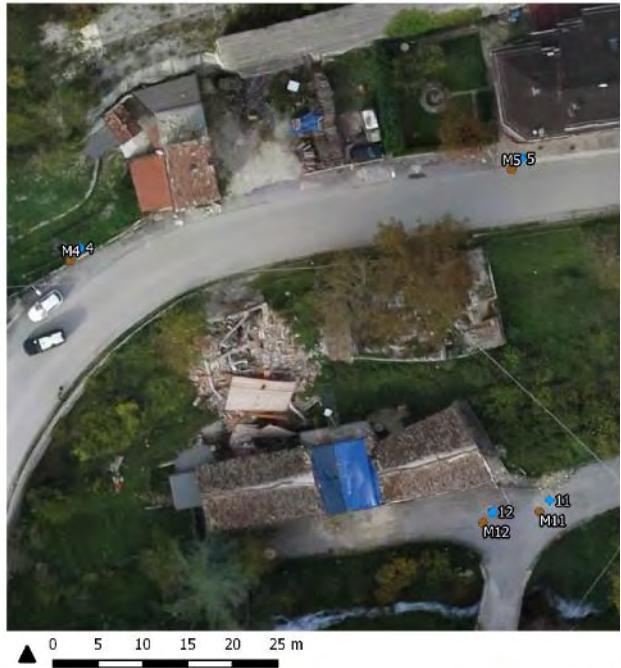
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DATA ANALYSIS AND VALIDATION

1-ACQUISITION
2-GEOREFERENTIATION

GeoTag



Legenda

- ◆ CP su modello GeoTag
- rtk GNSS



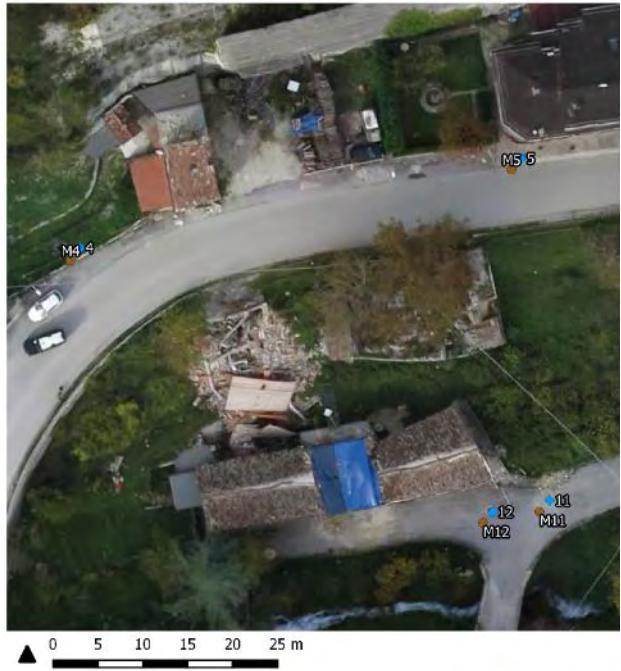
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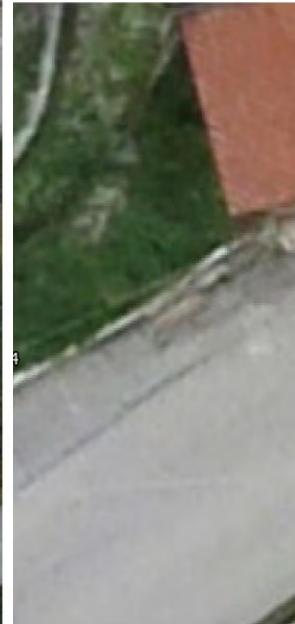
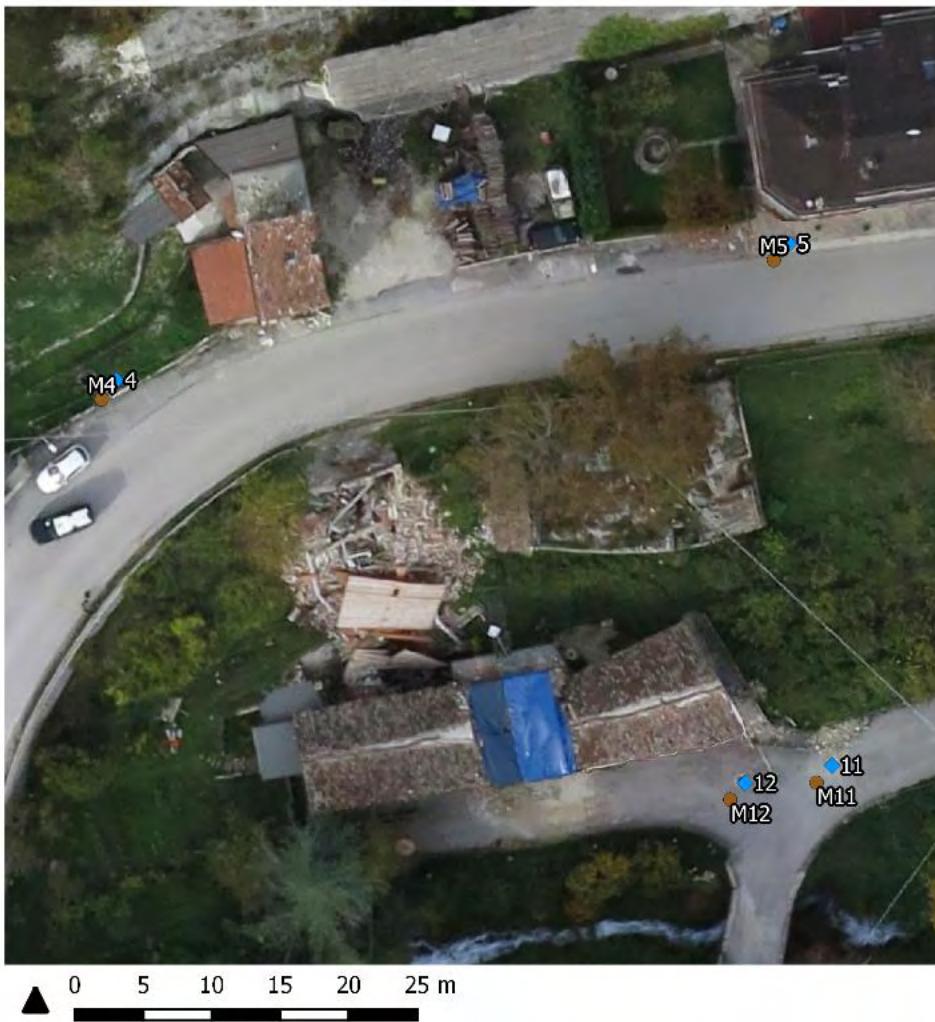
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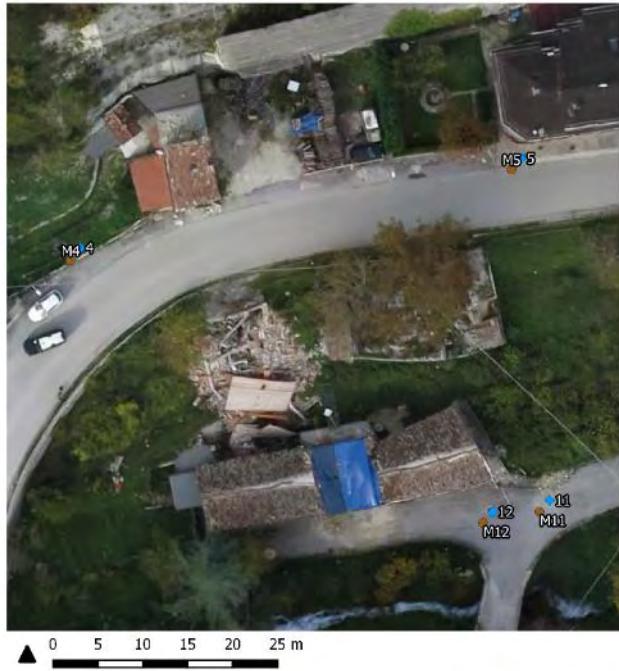
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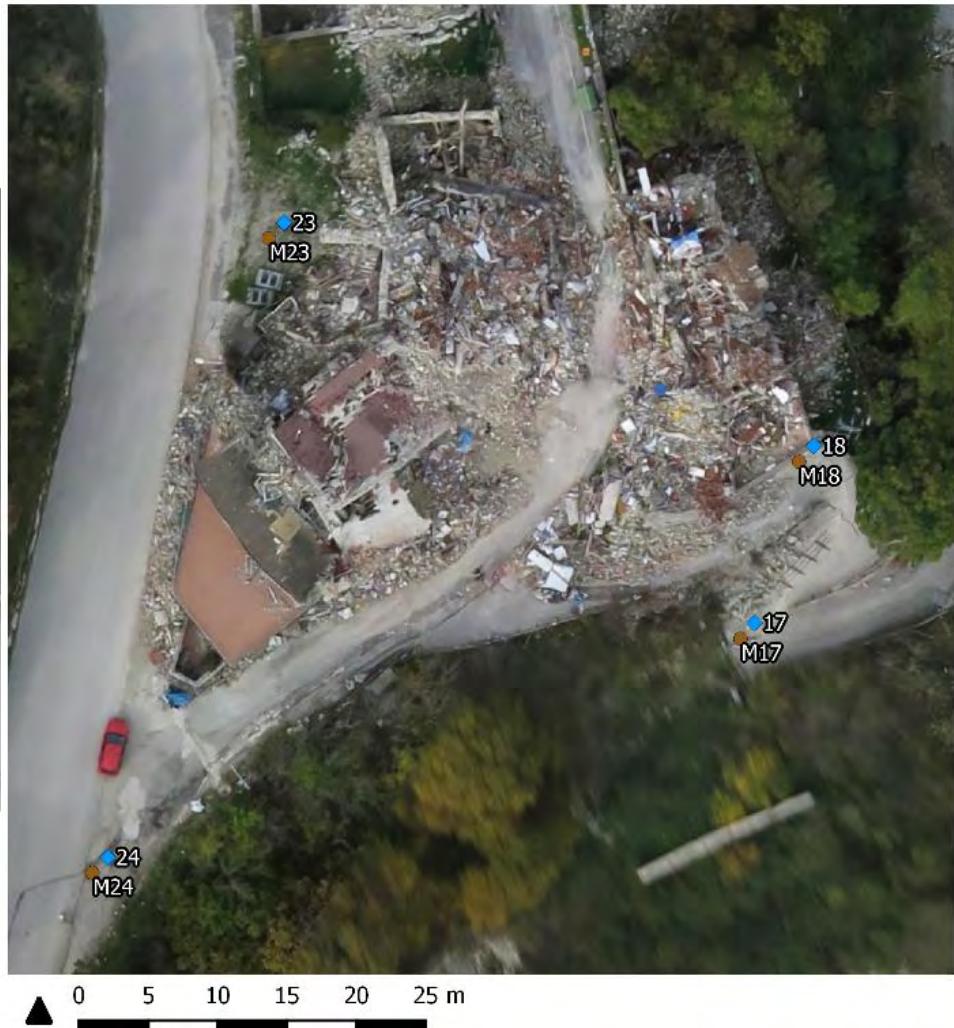
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DIFFERENT USED STRATEGIES	N° CPs	Mean on the CPs (m)			
		X	Y	Z	error
GEODETIC RTK <u>VS</u> portable GPS	10	2.264	1.488	9.608	4.453
GEODETIC RTK <u>VS</u> GeoTag	34	1.124	1.173	3.148	1.815



Mean accuracy on the residual measured with the portable GNSS and using the GeoTag

CONCLUSION AND FUTURE WORKS

- The proposed workflow underline the capacity of image-matching algorithms of obtaining suitable results in difficult scenarios as well
- The acquisition strategy need to be planned in order to combine different strips (perpendicular) or with oblique images as well
- The use of portable GNSS **doesn't** improve the accuracy during a photogrammetric process. According to our test the the GeoTag options need to be preferred.
- Define standard procedure for image acquisition GCPs measurements and data processing in emergency situation with UAV
- Deeply evaluate the Tie Points extraction algorithms in different scenario
- Realize strategy for change detection analysis on 2D images
- Improve the actual potentiality of UAV on board GNSS
- Define and develop platform for data management visualization and analysis

AKNOLEDGEMENTS

Politecnico di Torino (Task Force Terremoto Centro Italia – Prof. Sebastiano Foti) for supporting all the acquistion campaign in central Italy.

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GEER team (<http://www.geerassociation.org>), for the interesting collaboration during the on the field campaign.



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