

- when it has to be **right**



# Leica Geosystems Leica TerrainMapper-LN Calibration Certificate

<b>Product</b>	Leica TerrainMapper-LN
<b>Serial Number</b>	91515
<b>Date</b>	27 June 2019
<b>Inspector</b>	Mark O'Neal




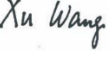

# 1. System Components

Component	Type	Serial Number
Pod	TerrainMapper Pod	91515
GNSS/IMU	Litef LCI-100C 500 Hz	1226
LiDAR Unit	Hyperion2 LiDAR Unit	5516
Camera Head	CH82	82658
Lens	NAT-D 2.8/80	80253

# 2. Estimation Process

		Passed	Date	Inspector
Image Flight	completed	ok	10.05.2019	Philip Benz
Image Quality Check	checked	ok	16.05.2019	Bernhard Riedl
Image Calibration	completed	ok	23.05.2019	Xu Wang
Image Misalignment Update	completed	ok	25.06.2019	Mark O'Neal
LiDAR Flight	completed	ok	29.11.2018	Philip Benz
LiDAR Quality Check	checked	ok	06.12.2018	Rene Heierli
LiDAR Calibration and Accuracy	completed	ok	12.12.2018	Robert Bosch
LiDAR Misalignment Update	completed	ok	27.06.2019	Mark O'Neal

# 3. Inspectors

<b>Name</b>	Bernhard Riedl	27.06.2019	
<b>Position</b>	Production Manager		
<b>Name</b>	Xu Wang	27.06.2019	
<b>Position</b>	Support Engineer		
<b>Name</b>	Robert Bosch	12.12.2018	
<b>Position</b>	Support Engineer		

# 4. Remarks

## 5. LiDAR Calibration Results

The calibration results for the LiDAR Unit are only valid for:

- IMU and Pod as listed in the System Components section

### 5.1 LiDAR Geometric Calibration Results

<b>IMU Misalignment</b>		<b>Value</b>	<b>Unit</b>
	$\omega$	-0.017122	degree
	$\Phi$	0.048251	degree
	$\kappa$	0.000135	degree
<b>Boresight</b>		<b>Value</b>	<b>Unit</b>
	$\Theta$	0.015419	degree
	$\Phi$	-0.001923	degree
<b>Receiver 1</b>		<b>Value</b>	<b>Unit</b>
Range	$\Delta$ Offset	0.000000	meters
<b>Wedge 0</b>		<b>Value</b>	<b>Unit</b>
Wedge	$\Delta$ Alpha	-0.043014	degree
Wedge Position	$\Delta$ Offset	0.442789	degree
Position Correction	X	-0.012826	degree
	Y	0.000012	degree
Mount	Roll	0.045379	degree
	Pitch	0.210132	degree
Rotation Axis	Roll	0.031087	degree
	Pitch	0.076675	degree
<b>Wedge 1</b>		<b>Value</b>	<b>Unit</b>
Wedge	$\Delta$ Alpha	-0.005517	degree
Wedge Position	$\Delta$ Offset	0.559649	degree
Position Correction	X	0.030760	degree
	Y	-0.001169	degree
Mount	Roll	0.012366	degree
	Pitch	0.054254	degree
	Speed Pitch	1.50E-06	degree/rps <sup>2</sup>
Rotation Axis	Roll	0.032485	degree
	Pitch	-0.029191	degree

#### LiDAR Geometric Calibration File

HYPERION\_GEOMETRY\_LIDARUNIT-5516-C-855570-DATETIME-20181204-161828.XML

	Date	12.04.2018
<b>LiDAR Misalignment Flight</b>	Date	06.14.2019
<b>LiDAR Misalignment Update Completed</b>	Date	06.27.2019

## 5.2 LiDAR Unit Accuracy Check

Accuracy checks:

- Deviation of two perpendicular lines to GCP's
- Difference of two perpendicular lines
- Difference of forward and backward scan of one line

### 5.2.1 Multi-line accuracy of two perpendicular lines to ground control points

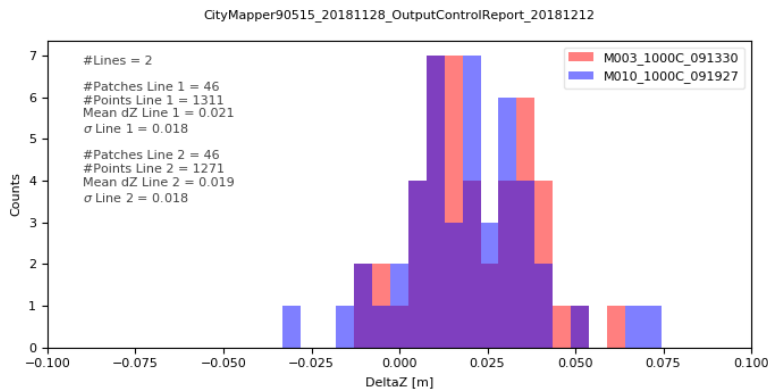


Figure 1 Vertical distance to ground control points at 1000 m AGL.

### 5.2.2 Difference of forward and backward scan of one line

M010\_1000C\_091927

303355 valid patches with size of 2 m found. Only patches with standard deviation < 0.05 m and minimum of 5 points are included.

Color	Limits [m]	Number of patches	Proportion of total number of patches [%]
Green	$\leq 0.04$	302593	99.75
Yellow	0.04-0.07	716	0.24
Orange	0.07-0.1	17	0.01
Red	$> 0.1$	29	0.01



Figure 2 Vertical difference between forward and backward scan at 1000 m AGL.

### 5.2.3 Multi-line accuracy between two perpendicular lines

### M003\_1000C\_091330\_vs\_M010\_1000C\_091927

29588 valid patches with size of 2 m found. Only patches with standard deviation < 0.05 m and minimum of 5 points are included.

Color	Limits [m]	Number of patches	Proportion of total number of patches [%]
Dark Green	<=0.04	29546	99.86
Bright Green	0.04-0.07	38	0.13
Yellow	0.07-0.1	1	0.00
Red	>0.1	3	0.01



Vertical difference

Figure 3 Vertical difference between two perpendicular lines at 1000 m AGL.

## 6. Imaging Sensors Estimation Results

The estimation results for the camera head and lens combination are only valid for:

- IMU and Pod as listed in the System Components section.
- Camera Head, lens and specified position as listed in the Estimation Results sections.

### 6.1 Camera Model of distortion free images

All factory calibration results contain fixed nominal focal lengths and zero principal point offsets. Leica HxMap applies the grid to create distortion-free images of nominal focal length and pixel size.

#### 6.1.1 CH8x Model

<b>Camera Head</b>		<b>Component</b>	
<b>Lens</b>		CH82	
		NAT-D 2.8/80	
<b>Camera Model</b>			
<b>Focal Length</b>		<b>Distance [mm]</b>	
	c		83.00
<b>Radial Symmetric Distorsion</b>		<b>Distance [mm]</b>	
	k <sub>0</sub>		0.0000
	k <sub>1</sub>		0.0000
	k <sub>2</sub>		0.0000
<b>Decentering Distortion</b>		<b>Distance [mm]</b>	
	p <sub>1</sub>		0.0000
	p <sub>2</sub>		0.0000
<b>Non-Orthogonality Distortion</b>		<b>Distance [mm]</b>	
	b <sub>1</sub>		0.0000
	b <sub>2</sub>		0.0000
<b>Pixel Size (Height and Width)</b>		<b>Distance [mm]</b>	
	RGB		0.0052
	NIR		0.0120
<b>Rows and Columns</b>		<b>Rows</b>	<b>Columns</b>
	Active RGB	7752	10320
	Raw RGB	7788	10336
	Active NIR	3654	4478
	Raw NIR	3366	4500

## 6.2 Results of Geometric Calibration

### 6.2.1 Calibration method for Green Reference Band

Estimation of additional parameters (focal length, principal point, radial symmetric distortion, correction grid) and IMU misalignment in simultaneous bundle adjustment

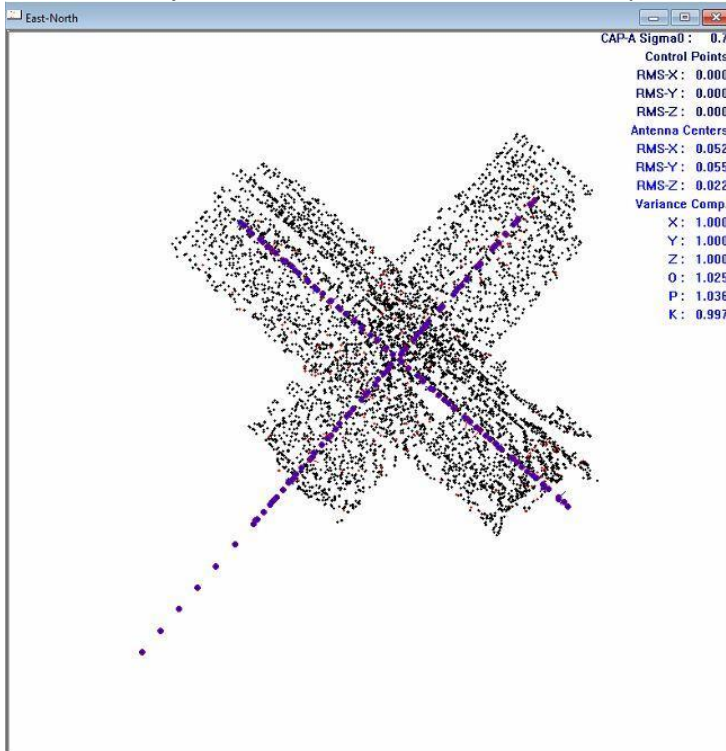
#### Reference band (green)

Distance [mm]

Resulting sigma naught of bundle adjustment:

0.0007

Final bundle adjustment results after elimination of tie point blunders:



### 6.2.2 Calibration method for Other Spectral Bands

Estimation of additional parameters (correction grid), based on the result for green in simultaneous bundle adjustment

#### Other Spectral Bands

Distance [mm]

Co-registration to green better than:

0.002

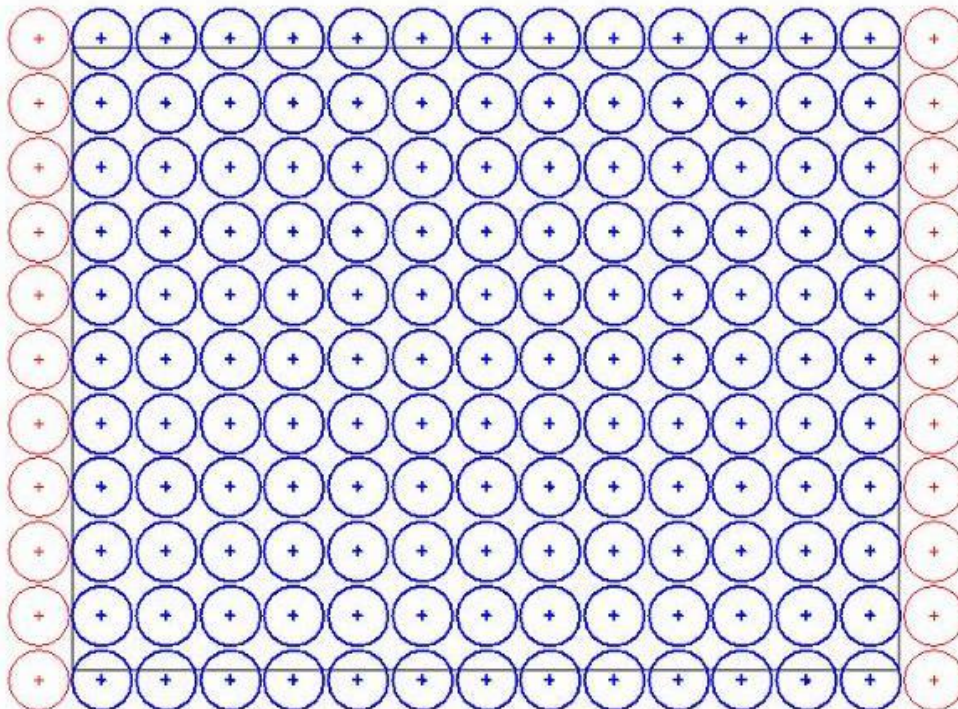
Leica HxMap applies the grid to create distortion-free images of nominal focal length and fixed pixel size of 0.0052 mm.

### 6.3 Estimation Results for Nadir Camera Head and Lens

	<b>Component</b>	<b>Serial Number</b>
<b>Camera Head</b>	CH82	82658
<b>Lens</b>	NAT-D 2.8/80	80253
<b>View Direction in Pod Position</b>	Nadir	
<b>IMU Misalignment</b>	<b>Angle [degree]</b>	
	$\omega$	0.07949
	$\phi$	-0.00801
	$\kappa$	-0.22593
<b>Principal Point</b>	<b>Distance [mm]</b>	
	x	0.0000
	y	0.0000
<b>Focal Length</b>	<b>Distance [mm]</b>	
	c	83.00
<b>Geometric Calibration File</b>		
RCD30_Geometry_CameraHead-82658-E-798528_LensSystem-80253-B-785423_DateTime-20190521-110247.xml		
<b>Geometric Calibration Date</b>	Date	21.05.2019
<b>Radiometric Calibration Date</b>	Date	05.06.2019
<b>Misalignment Flight</b>	Date	14.06.2019
<b>Misalignment Update Completed</b>	Date	25.06.2019

Remaining image space residuals after applying the calibration results

RMS-X: 0.06  
RMS-Y: 0.06



Radius of circles is 0.0007 mm