

UAV-based multi-sensor datasets for geospatial research - USEGEO

Principal Investigator:	
Co-Investigator: H	

MAIN MOTIVATIONS, OBJECTIVES AND PARTNERSHIPS

BENCHMARK DATA COLLECTION – COMPLETION OF THE WORK



Figure 1 – The used drone and technical specifications of the payload



Figure 2 – Example of LiDAR point cloud, and the corresponding true orthophoto in correspondence of Area 1

DATA PROCESSING



Table 1: Mean C2C distances between LiDAR and camera point clouds after hybrid adjustment



Figure 4. For each image of known orientation parameters, a GT depth map is generated by projecting the LiDaR 3D points

EVALUATION CRITERIA AND PROCEDURES

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Figure 5. Examples of SIDE results: input image (1st column), ground truth (2nd column) and corresponding results (3rd column)

DATA DELIVERY

DISSEMINATION

References