

Contents

1	Introduction — 1
1.1	Overview — 1
1.1.1	Content — 1
1.1.2	References — 2
1.2	Fundamental methods — 2
1.2.1	The photogrammetric process — 2
1.2.2	Aspects of photogrammetry — 4
1.2.3	Image-forming model — 7
1.2.4	Photogrammetric systems and procedures — 10
1.2.4.1	Digital system — 10
1.2.4.2	Recording and analysis procedures — 12
1.2.5	Photogrammetric products — 14
1.3	Application areas — 15
1.4	Historical development — 18
2	Mathematical fundamentals — 32
2.1	Coordinate systems — 32
2.1.1	Pixel and sensor coordinate system — 32
2.1.2	Image and camera coordinate systems — 33
2.1.3	Model coordinate system — 34
2.1.4	Object coordinate system — 35
2.2	Coordinate transformations — 36
2.2.1	Plane transformations — 36
2.2.1.1	Homogenous coordinates — 36
2.2.1.2	Similarity transformation — 37
2.2.1.3	Affine transformation — 38
2.2.1.4	Polynomial transformation — 39
2.2.1.5	Bilinear transformation — 40
2.2.1.6	Projective transformation — 41
2.2.2	Spatial rotations — 44
2.2.2.1	Rotation matrix using trigonometric functions — 44
2.2.2.2	Rotation matrix using quaternions — 47
2.2.2.3	Rodrigues rotation matrix — 50
2.2.2.4	Rotation matrix with direction cosines — 50
2.2.2.5	Normalization of rotation matrices — 50
2.2.2.6	Comparison of coefficients — 51
2.2.3	Spatial transformations — 52
2.2.3.1	General transformations — 52
2.2.3.2	Central projection — 54

2.2.3.3	General affine transformation — 55
2.2.4	Spatial similarity transformation — 56
2.2.4.1	Mathematical model — 56
2.2.4.2	Approximate values — 58
2.2.4.3	Calculation with eigenvalues and quaternions — 61
2.2.5	Additional coordinate transformations — 62
2.2.5.1	Spherical coordinates — 62
2.2.5.2	Cylindrical coordinates — 63
2.3	Geometric elements — 63
2.3.1	Analytical geometry in the plane — 65
2.3.1.1	Straight line — 65
2.3.1.2	Circle — 68
2.3.1.3	Ellipse — 69
2.3.1.4	Curves — 72
2.3.2	Analytical geometry in 3D space — 76
2.3.2.1	Straight line — 76
2.3.2.2	Plane — 79
2.3.2.3	Rotationally symmetric shapes — 82
2.3.3	Surfaces — 87
2.3.3.1	Digital surface model — 88
2.3.3.2	Digital volume model (voxel) — 90
2.3.3.3	Range images — 90
2.3.3.4	B-spline and Bézier surfaces — 92
2.4	Adjustment techniques — 93
2.4.1	The problem — 93
2.4.1.1	Functional model — 93
2.4.1.2	Stochastic model — 95
2.4.2	Least-squares method (Gauss-Markov linear model) — 96
2.4.2.1	Adjustment of direct observations — 96
2.4.2.2	General least squares adjustment — 97
2.4.2.3	Levenberg-Marquardt algorithm — 99
2.4.2.4	Conditional least squares adjustment — 100
2.4.3	Quality measures — 101
2.4.3.1	Accuracy measures — 102
2.4.3.2	Confidence interval — 104
2.4.3.3	Correlations — 106
2.4.3.4	Reliability — 107
2.4.3.5	Precision of calculated coordinates — 111
2.4.4	Error detection in practice — 112
2.4.4.1	Error detection without adjustment — 114
2.4.4.2	Data snooping — 114
2.4.4.3	Variance component estimation — 114

2.4.4.4	Robust estimation with weighting functions —	115
2.4.4.5	Robust estimation according to L1 norm —	116
2.4.4.6	RANSAC —	117
2.4.5	Computational aspects —	118
2.4.5.1	Linearization —	118
2.4.5.2	Normal systems of equations —	118
2.4.5.3	Sparse matrix techniques and optimization —	119

3 Imaging technology — 121

3.1	Physics of image formation —	121
3.1.1	Wave optics —	121
3.1.1.1	Electro-magnetic spectrum —	121
3.1.1.2	Radiometry —	122
3.1.1.3	Refraction and reflection —	123
3.1.1.4	Diffraction —	125
3.1.1.5	Polarization —	127
3.1.2	Optical imaging —	128
3.1.2.1	Geometric optics —	128
3.1.2.2	Apertures and stops —	130
3.1.2.3	Focussing —	131
3.1.2.4	Scheimpflug condition —	134
3.1.3	Aberrations —	135
3.1.3.1	Distortion —	136
3.1.3.2	Chromatic aberration —	137
3.1.3.3	Spherical aberration —	138
3.1.3.4	Astigmatism and curvature of field —	139
3.1.3.5	Light fall-off and vignetting —	140
3.1.4	Aspherical lenses —	141
3.1.5	Resolution —	143
3.1.5.1	Resolving power of a lens —	143
3.1.5.2	Geometric resolving power —	144
3.1.5.3	Contrast and modulation transfer function —	145
3.1.6	Fundamentals of sampling theory —	147
3.1.6.1	Sampling theorem —	147
3.1.6.2	Detector characteristics —	149
3.2	Photogrammetric imaging concepts —	151
3.2.1	Offline and online systems —	151
3.2.1.1	Offline photogrammetry —	152
3.2.1.2	Online photogrammetry —	152
3.2.2	Imaging configurations —	153
3.2.2.1	Single image acquisition —	153
3.2.2.2	Stereo image acquisition —	153

3.2.2.3	Multi-image acquisition — 154
3.3	Geometry of the camera as a measuring device — 155
3.3.1	Image scale and accuracy — 155
3.3.1.1	Image scale — 155
3.3.1.2	Accuracy estimation — 158
3.3.2	Interior orientation of a camera — 159
3.3.2.1	Physical definition of the image coordinate system — 160
3.3.2.2	Perspective centre and distortion — 161
3.3.2.3	Parameters of interior orientation — 163
3.3.2.4	Metric and semi-metric cameras — 165
3.3.2.5	Determination of interior orientation (calibration) — 166
3.3.3	Standardized correction functions — 168
3.3.3.1	Radial distortion — 168
3.3.3.2	Tangential distortion — 173
3.3.3.3	Affinity and shear — 174
3.3.3.4	Total correction — 175
3.3.4	Alternative correction formulations — 176
3.3.4.1	Simplified models — 176
3.3.4.2	Additional parameters — 176
3.3.4.3	Correction of distortion as a function of object distance — 178
3.3.4.4	Image-variant calibration — 180
3.3.4.5	Correction of local image deformations — 181
3.3.4.6	Chromatic aberration — 183
3.3.5	Iterative correction of imaging errors — 184
3.3.6	Transformation of interior orientation parameters — 186
3.3.7	Fisheye projections — 187
3.4	System components — 189
3.4.1	Opto-electronic imaging sensors — 191
3.4.1.1	Principle of CCD sensor — 191
3.4.1.2	CCD area sensors — 193
3.4.1.3	CMOS matrix sensors — 195
3.4.1.4	Sensor formats — 196
3.4.1.5	Microlenses — 198
3.4.1.6	Colour cameras — 198
3.4.1.7	Sensor architecture — 202
3.4.1.8	Geometric properties — 202
3.4.1.9	Radiometric properties — 205
3.4.2	Camera technology — 208
3.4.2.1	Camera types — 208
3.4.2.2	Shutter — 211
3.4.2.3	Image stabilization and cleaning — 214
3.4.2.4	Sensor to lens flange distance — 215

3.4.3	Lenses — 215
3.4.3.1	Relative aperture and f/number — 215
3.4.3.2	Field of view — 216
3.4.3.3	Image circle and sensor format — 217
3.4.3.4	Super wide-angle and fisheye lenses — 218
3.4.3.5	Zoom lenses — 219
3.4.3.6	Tilt-shift lenses — 220
3.4.3.7	Telecentric lenses — 222
3.4.3.8	Reflective optics — 223
3.4.3.9	Stereo image splitting — 224
3.4.4	Filters — 225
3.5	Imaging systems — 226
3.5.1	Industrial cameras — 226
3.5.2	Digital cameras — 228
3.5.3	High-speed cameras — 232
3.5.4	Stereo and multi-camera systems — 235
3.5.5	Micro and macro-scanning cameras — 237
3.5.5.1	Micro scanning — 237
3.5.5.2	Macro scanning — 238
3.5.6	Panoramic cameras — 240
3.5.6.1	Line scanners — 240
3.5.6.2	Panorama stitching — 241
3.5.6.3	Panoramas from fisheye lenses — 243
3.5.7	Endoscopes — 244
3.5.8	Thermal imaging cameras — 245
3.5.9	Multi-spectral and hyperspectral cameras — 246
3.5.9.1	Multi-spectral cameras — 246
3.5.9.2	Hyperspectral cameras — 247
3.6	Reflection and illumination — 249
3.6.1	Reflection models — 249
3.6.1.1	Reflection types — 249
3.6.1.2	Retro-reflection — 251
3.6.2	High contrast photogrammetric targeting — 252
3.6.2.1	Retro-reflective targets — 252
3.6.2.2	Other target materials — 254
3.6.3	Illumination and projection techniques — 255
3.6.3.1	Electronic flash — 255
3.6.3.2	Pattern projection — 257
3.6.3.3	Laser projectors — 258
3.6.3.4	Directional lighting — 259
3.6.3.5	Reflectance Transformation Imaging — 261

4 Analytical methods — 263

- 4.1 Overview — 263
- 4.2 Processing of single images — 265
 - 4.2.1 Exterior orientation — 265
 - 4.2.1.1 Standard case — 265
 - 4.2.1.2 Special case of terrestrial photogrammetry — 267
 - 4.2.2 Collinearity equations — 268
 - 4.2.3 Space resection — 272
 - 4.2.3.1 Space resection with known interior orientation — 273
 - 4.2.3.2 Space resection with unknown interior orientation — 275
 - 4.2.3.3 Approximate values for resection — 276
 - 4.2.3.4 Resection with minimum object information — 276
 - 4.2.3.5 Quality measures — 279
 - 4.2.4 Linear orientation methods — 280
 - 4.2.4.1 Direct linear transformation (DLT) — 280
 - 4.2.4.2 Perspective projection matrix — 282
 - 4.2.5 Object position and orientation (pose) by inverse resection — 284
 - 4.2.5.1 Position and orientation of an object with respect to a camera — 284
 - 4.2.5.2 Position and orientation of one object relative to another — 284
 - 4.2.6 Projective transformation of a plane — 287
 - 4.2.6.1 Mathematical model — 287
 - 4.2.6.2 Influence of interior orientation — 290
 - 4.2.6.3 Influence of non-coplanar object points — 290
 - 4.2.6.4 Measurement of flat objects — 291
 - 4.2.7 Monoplotting — 292
 - 4.2.7.1 Standard geometric shapes (geometric primitives) — 292
 - 4.2.7.2 Digital surface models — 293
 - 4.2.8 Rectification — 295
 - 4.2.8.1 Plane rectification — 295
 - 4.2.8.2 Differential rectification (orthophotos) — 296
 - 4.2.8.3 Image mosaics — 301
- 4.3 Processing of stereo images — 303
 - 4.3.1 Stereoscopic principle — 303
 - 4.3.1.1 Stereoscopic matching — 303
 - 4.3.1.2 Tie points — 304
 - 4.3.1.3 Orientation of stereo image pairs — 305
 - 4.3.1.4 Normal case of stereo photogrammetry — 306
 - 4.3.2 Epipolar geometry — 307
 - 4.3.3 Relative orientation — 309
 - 4.3.3.1 Coplanarity constraint — 311
 - 4.3.3.2 Calculation — 312
 - 4.3.3.3 Model coordinates — 313

4.3.3.4	Calculation of epipolar lines —	314
4.3.3.5	Calculation of normal-case images (epipolar images) —	315
4.3.3.6	Quality of relative orientation —	317
4.3.3.7	Special cases of relative orientation —	319
4.3.4	Fundamental matrix and essential matrix —	321
4.3.5	Absolute orientation —	323
4.3.5.1	Mathematical model —	323
4.3.5.2	Definition of the datum —	325
4.3.5.3	Calculation of exterior orientations —	325
4.3.5.4	Calculation of relative orientation from exterior orientations —	325
4.3.6	Stereoscopic processing —	326
4.3.6.1	Principle of stereo image processing —	326
4.3.6.2	Point determination using image coordinates —	328
4.3.6.3	Point determination with floating mark —	334
4.4	Multi-image processing and bundle adjustment —	336
4.4.1	General remarks —	336
4.4.1.1	Objectives —	336
4.4.1.2	Development —	337
4.4.1.3	Data flow —	339
4.4.2	Mathematical model —	341
4.4.2.1	Adjustment model —	341
4.4.2.2	Normal equations —	343
4.4.2.3	Combined adjustment of photogrammetric and survey observations —	347
4.4.2.4	Adjustment of additional parameters —	351
4.4.3	Object coordinate system (definition of datum) —	353
4.4.3.1	Rank and datum defect —	353
4.4.3.2	Reference points —	355
4.4.3.3	Direct georeferencing —	358
4.4.3.4	Free net adjustment —	358
4.4.4	Generation of approximate values —	362
4.4.4.1	Strategies for the automatic calculation of approximate values —	364
4.4.4.2	Initial value generation by automatic point measurement —	368
4.4.4.3	Practical aspects of the generation of approximate values —	369
4.4.5	Quality measures and analysis of results —	371
4.4.5.1	Output report —	371
4.4.5.2	Sigma 0 and reprojection error —	371
4.4.5.3	Precision of image coordinates —	372
4.4.5.4	Precision of object coordinates —	373
4.4.5.5	Quality of self-calibration —	374
4.4.6	Strategies for bundle adjustment —	376
4.4.6.1	Simulation —	376

4.4.6.2	Divergence —	377
4.4.6.3	Elimination of gross errors —	378
4.4.7	Multi-image calculation of points and geometric elements —	378
4.4.7.1	General spatial intersection —	379
4.4.7.2	Direct determination of geometric elements —	381
4.5	Panoramic photogrammetry —	382
4.5.1	Cylindrical panoramic imaging model —	382
4.5.2	Orientation of panoramic imagery —	385
4.5.2.1	Approximate values —	385
4.5.2.2	Space resection —	386
4.5.2.3	Bundle adjustment —	386
4.5.3	Epipolar geometry —	387
4.5.4	Spatial intersection —	389
4.5.5	Rectification of panoramic images —	389
4.5.5.1	Orthogonal rectification —	389
4.5.5.2	Tangential images —	390
4.6	Multi-media photogrammetry —	391
4.6.1	Light refraction at media interfaces —	391
4.6.1.1	Media interfaces —	391
4.6.1.2	Plane parallel media interfaces —	392
4.6.1.3	Spherical media interfaces —	395
4.6.1.4	Ray tracing through refracting interfaces —	396
4.6.2	Extended model of bundle triangulation —	398
4.6.2.1	Object-invariant interfaces —	398
4.6.2.2	Bundle-invariant interfaces —	399
4.6.3	Special aspects of underwater photogrammetry —	400
5	Digital image analysis —	402
5.1	Fundamentals —	402
5.1.1	Image processing procedure —	402
5.1.2	Pixel coordinate system —	404
5.1.3	Handling image data —	405
5.1.3.1	Image pyramids —	405
5.1.3.2	Data formats —	406
5.1.3.3	Image compression —	409
5.1.3.4	Video formats —	410
5.1.3.5	Integral images —	411
5.2	Image pre-processing —	413
5.2.1	Point operations —	413
5.2.1.1	Histogram —	413
5.2.1.2	Lookup tables —	414
5.2.1.3	Contrast enhancement —	415

5.2.1.4	Thresholding — 417
5.2.1.5	Image arithmetic — 419
5.2.2	Colour operations — 420
5.2.2.1	Colour spaces — 420
5.2.2.2	Colour transformations — 423
5.2.2.3	Colour calibration — 426
5.2.2.4	Colour combinations — 427
5.2.3	Filter operations — 429
5.2.3.1	Spatial domain and frequency domain — 429
5.2.3.2	Smoothing filters — 432
5.2.3.3	Morphological operations — 434
5.2.3.4	Wallis filter — 436
5.2.4	Edge extraction — 438
5.2.5	First order differential filters — 439
5.2.5.1	Second order differential filters — 441
5.2.5.2	Laplacian of Gaussian filter — 442
5.2.5.3	Image sharpening — 443
5.2.5.4	Hough transform — 444
5.2.5.5	Enhanced edge operators — 445
5.2.5.6	Sub-pixel interpolation — 447
5.3	Geometric image transformation — 450
5.3.1	Fundamentals of rectification — 451
5.3.2	Grey value interpolation — 452
5.3.3	Textured images — 455
5.3.3.1	Texture mapping — 455
5.3.3.2	Synthetic images — 457
5.4	Digital processing of single images — 457
5.4.1	Approximate values — 458
5.4.1.1	Possibilities — 458
5.4.1.2	Segmentation of point features — 458
5.4.2	Measurement of single point features — 460
5.4.2.1	On-screen measurement — 460
5.4.2.2	Centroid methods — 460
5.4.2.3	Correlation methods — 462
5.4.2.4	Least-squares matching — 464
5.4.2.5	Structural measuring methods — 469
5.4.2.6	Accuracy issues — 472
5.4.3	Feature extraction — 473
5.4.3.1	Interest operators and feature detectors — 473
5.4.3.2	Förstner operator — 474
5.4.3.3	SUSAN operator — 476
5.4.3.4	FAST operator — 477

5.4.3.5	SIFT operator — 478
5.4.3.6	SURF Operator — 481
5.4.3.7	ORB operator — 481
5.5	Image matching and 3D object reconstruction — 482
5.5.1	Overview — 482
5.5.2	Strategies for matching non-oriented images — 486
5.5.2.1	Coded targets — 486
5.5.2.2	Structure-from-motion — 486
5.5.2.3	Image masking — 488
5.5.3	Similarity measures — 489
5.5.3.1	Sums of differences — 490
5.5.3.2	Census and Hamming distance — 490
5.5.3.3	Hashing — 491
5.5.3.4	Normalized cross-correlation — 492
5.5.3.5	Least-squares matching — 492
5.5.3.6	Euclidian distance between feature vectors — 492
5.5.4	Correspondence analysis based on epipolar geometry — 493
5.5.4.1	Matching in image pairs — 493
5.5.4.2	Semi-global matching — 495
5.5.5	Multi-image matching — 499
5.5.5.1	Multi-View Stereo — 499
5.5.5.2	Matching in oriented image triples — 499
5.5.5.3	Matching in an unlimited number of images — 502
5.5.5.4	Multi-image least-squares matching — 502
5.5.6	Matching methods with object models — 507
5.5.6.1	Object-based multi-image matching — 507
5.5.6.2	Multi-image matching with surface grids — 511
5.5.6.3	Object-based semi-global multi-image matching (OSGM) — 513
5.5.6.4	Additional object-based matching methods — 516
5.5.7	Matching in image sequences — 519
5.5.7.1	2D object tracking in single-camera sequences — 520
5.5.7.2	Target tracking — 520
5.5.7.3	3D object reconstruction from single-camera image sequences — 523
5.5.7.4	Object tracking in multi-camera image sequences — 524
5.5.7.5	Prediction of subsequent points (Kalman filter) — 525
5.5.7.6	Simultaneous Localization and Mapping (SLAM) — 527
6	Measuring tasks and systems — 529
6.1	Overview — 529
6.2	Targeting — 529
6.2.1	Target designs — 530
6.2.1.1	Circular targets — 530

6.2.1.2	Spherical targets —	532
6.2.1.3	Patterned targets —	534
6.2.1.4	Coded targets —	534
6.2.2	Target systems —	536
6.2.2.1	Centring targets —	536
6.2.2.2	Probes —	536
6.2.2.3	Hidden-point devices —	537
6.2.2.4	6DOF targets —	539
6.3	Realization of reference systems —	540
6.3.1	References —	540
6.3.1.1	Definition of scale —	540
6.3.1.2	Definition of reference coordinate systems —	542
6.3.2	Measurement systems —	543
6.3.2.1	Video total stations and multistations —	543
6.3.2.2	Laser trackers —	544
6.4	Interactive multi-image processing systems —	546
6.4.1	Programs with CAD functionality —	546
6.4.2	Structure-from-motion programs —	548
6.4.3	Offline processing systems for industrial applications —	549
6.4.4	Educational software —	550
6.5	Tactile probing systems —	552
6.5.1	Measurement principle —	552
6.5.2	Single-camera systems —	553
6.5.2.1	Camera with hand-held probe —	553
6.5.2.2	Probing system with integrated camera —	554
6.5.3	Stereo and multi-camera systems —	555
6.6	Industrial measuring systems for single point features —	557
6.6.1	Mobile industrial point measuring-systems —	557
6.6.1.1	Offline photogrammetric systems —	557
6.6.1.2	Online photogrammetric systems —	559
6.6.1.3	Stereo vision systems —	562
6.6.2	Static industrial online measuring systems —	564
6.6.2.1	Tube inspection system —	565
6.6.2.2	Steel-plate positioning system —	566
6.6.2.3	Multi-camera system with projected point arrays —	567
6.7	Systems for surface measurement —	568
6.7.1	Overview —	568
6.7.1.1	Active and passive systems —	568
6.7.1.2	Surface textures for area-based measurement —	569
6.7.2	Laser triangulation —	571
6.7.3	Fringe projection systems —	571
6.7.3.1	Stationary fringe projection —	571

6.7.3.2	Dynamic fringe projection (phase-shift method) —	573
6.7.3.3	Coded light (Gray code) —	574
6.7.3.4	Aperiodic fringe projection —	575
6.7.3.5	Single-camera fringe-projection systems —	576
6.7.3.6	Multi-camera fringe-projection systems —	578
6.7.4	Point and grid projection —	580
6.7.4.1	Multi-camera systems with target grid projection —	580
6.7.4.2	Multi-camera system with grid projection —	581
6.7.4.3	Multi-camera system with regular etched patterns —	582
6.7.5	Systems utilizing random patterns —	582
6.7.5.1	Dual-camera system with projection of random patterns —	583
6.7.5.2	Surface measurement with textured adhesive film —	584
6.7.5.3	Measurement of dynamic surface change —	584
6.7.6	Range cameras —	587
6.7.6.1	Kinect —	587
6.7.6.2	Current generation range cameras —	589
6.7.6.3	Light-field cameras —	590
6.8	Laser-scanning systems —	591
6.8.1	3D laser scanners —	591
6.8.2	2D and 1D laser scanning —	598
6.8.3	Panoramic imaging systems with laser distance measurement —	599
6.9	Registration and orientation of images and scans —	600
6.9.1	Multi-image photogrammetry —	601
6.9.2	Orientation with object points —	602
6.9.2.1	Orientation with unknown reference targets —	602
6.9.2.2	Orientation with known reference targets —	603
6.9.2.3	Orientation with known feature points —	604
6.9.3	Scanner location by optical tracking —	604
6.9.4	Mechanical location of scanners —	606
6.9.5	Orientation with external systems and reference points —	607
6.9.6	Connecting point clouds (registration) —	609
6.9.6.1	Registration with 3D reference targets —	609
6.9.6.2	Iterative closest point (ICP) —	610
6.9.7	ICP-based scanner devices —	612
6.10	Dynamic photogrammetry —	612
6.10.1	Relative movement between object and imaging system —	613
6.10.1.1	Static object —	613
6.10.1.2	Moving object —	615
6.10.2	Recording dynamic sequences —	616
6.10.2.1	Camera system for robot calibration —	616
6.10.2.2	High-speed 6 DOF system —	617
6.10.2.3	Recording with high-speed cameras —	618

6.10.2.4	Particle Image Velocimetry —	619
6.10.3	Motion capture (MoCap) —	620
6.11	Mobile measurement platforms —	621
6.11.1	Mobile mapping systems —	621
6.11.1.1	Outdoor mapping —	621
6.11.1.2	Indoor mapping —	622
6.11.2	Close-range aerial imagery —	624
6.11.2.1	Aerial systems —	624
6.11.2.2	Sensor technology —	626
6.11.2.3	Flight planning —	628
6.11.2.4	Photogrammetric processing —	631
6.12	Visualisation systems —	633
6.12.1	Digital stereo viewing systems —	633
6.12.2	AR/VR systems —	635
6.12.2.1	VR systems —	635
6.12.2.2	AR/MR systems —	636
6.12.3	Industrial 3D projection systems —	637
7	Measurement design and quality —	639
7.1	Project planning —	639
7.1.1	Planning criteria —	639
7.1.2	Accuracy issues —	640
7.1.3	Restrictions on imaging configuration —	641
7.1.4	Accuracy estimation by simulation —	644
7.1.4.1	Variance-covariance propagation —	644
7.1.4.2	Monte Carlo simulation —	646
7.1.4.3	Unscented transformation —	649
7.1.4.4	Bootstrap simulation —	650
7.1.5	Design of the imaging configuration —	651
7.1.5.1	Network design —	651
7.1.5.2	Scale —	653
7.2	Quality measures and performance testing —	655
7.2.1	Statistical parameters —	656
7.2.1.1	Precision and accuracy parameters from a bundle adjustment —	656
7.2.1.2	Accuracy —	657
7.2.1.3	Relative accuracy —	658
7.2.2	Metrological parameters —	658
7.2.2.1	Measurement uncertainty —	658
7.2.2.2	Reference value —	659
7.2.2.3	Measurement error —	660
7.2.2.4	Accuracy —	660
7.2.2.5	Precision —	660

7.2.2.6	Tolerance — 661
7.2.2.7	Resolution — 662
7.2.3	Acceptance and re-verification of measuring systems — 662
7.2.3.1	Definition of terms — 663
7.2.3.2	Differentiation from coordinate measuring machines (CMMs) — 665
7.2.3.3	Reference artefacts — 666
7.2.3.4	Testing of point-by-point measuring systems — 667
7.2.3.5	Testing of area-scanning systems — 671
7.3	Strategies for camera calibration — 675
7.3.1	Calibration methods — 675
7.3.1.1	Test-field calibration — 676
7.3.1.2	Plumb-line calibration — 679
7.3.1.3	On-the-job calibration — 680
7.3.1.4	Self-calibration — 680
7.3.1.5	System calibration — 681
7.3.2	Imaging configurations — 682
7.3.2.1	Calibration using a plane point field — 682
7.3.2.2	Calibration using a spatial point field — 683
7.3.2.3	Calibration with moving scale bar — 684
7.3.3	Calibration of multi-camera and non-standard imaging systems — 685
7.3.3.1	Calibration of stereo and multi-camera systems — 685
7.3.3.2	Calibration of fisheye cameras — 685
7.3.3.3	Calibration of underwater cameras — 687
7.3.4	Quality criteria for camera calibration — 687
7.3.5	Problems with self-calibration — 688
8	Example applications — 693
8.1	Architecture, archaeology and cultural heritage — 693
8.1.1	Photogrammetric building records — 693
8.1.1.1	Drawings — 695
8.1.1.2	3D building models — 696
8.1.1.3	Image plans and orthophotos — 696
8.1.2	Examples of photogrammetric building reconstructions — 697
8.1.2.1	Torhaus Seedorf — 697
8.1.2.2	The Milan Cathedral — 698
8.1.2.3	Lurji monastery — 700
8.2	Cultural heritage artefacts — 702
8.2.1	Art and museum pieces — 702
8.2.1.1	Statues and sculptures — 702
8.2.1.2	Death mask of pharaoh Tutankhamun — 703
8.2.1.3	Sarcophagus of the Spouses — 704

- 8.2.1.4 Goethe elephant skull — 706
- 8.2.2 Archaeological recordings — 707
- 8.2.2.1 3D record of Pompeii — 707
- 8.2.2.2 Temple of Hadrian — 708
- 8.2.2.3 Otzing burial chamber — 710
- 8.2.2.4 Survey of the Bremen cog — 711
- 8.2.2.5 Megalithic tomb Kleinenkneten — 713
- 8.3 3D city and landscape models — 715
- 8.3.1 City models — 715
- 8.3.2 Generation of terrain models from multi-spectral image data — 716
- 8.3.3 Landscape model from laser scanning and photogrammetry — 718
- 8.4 Engineering surveying and civil engineering — 719
- 8.4.1 3D modelling of complex objects — 719
- 8.4.1.1 As-built documentation — 719
- 8.4.1.2 Building Information Modelling — 720
- 8.4.1.3 Stairwell measurement — 722
- 8.4.2 Deformation analysis — 723
- 8.4.2.1 Deformation of concrete tanks — 723
- 8.4.2.2 Measurement of wind-turbine rotor blades — 724
- 8.4.3 Material testing — 727
- 8.4.3.1 Surface measurement of mortar joints in brickwork — 727
- 8.4.3.2 Structural loading tests — 728
- 8.4.4 Roof and façade measurement — 730
- 8.5 Industrial applications — 731
- 8.5.1 Power stations and production plants — 731
- 8.5.1.1 Wind power stations — 731
- 8.5.1.2 Particle accelerators — 734
- 8.5.2 Aerospace industry — 735
- 8.5.2.1 Inspection of tooling jigs — 735
- 8.5.2.2 Production control — 736
- 8.5.2.3 Visual checking — 736
- 8.5.2.4 Antenna measurement — 737
- 8.5.3 Car industry — 738
- 8.5.3.1 Rapid prototyping and reverse engineering — 739
- 8.5.3.2 Car safety tests — 740
- 8.5.3.3 Car body deformations — 742
- 8.5.4 Ship building industry — 743
- 8.6 Underwater photogrammetry — 744
- 8.6.1 Measurement of water and other fluid surfaces — 744
- 8.6.2 Underwater measurement of welds — 746
- 8.6.3 Underwater photogrammetry of the Costa Concordia shipwreck — 748

8.7	Medicine — 749
8.7.1	Surface measurement — 750
8.7.2	Online navigation systems — 751
8.8	Miscellaneous applications — 753
8.8.1	Forensic applications — 753
8.8.1.1	Accident recording — 753
8.8.1.2	Scene-of-crime recording — 754
8.8.1.3	Anthropological analyses — 756
8.8.2	Scientific applications — 756
8.8.2.1	Monitoring glacier movements — 757
8.8.2.2	Earth sciences — 758
8.8.2.3	Entomology — 760
8.8.2.4	Measurement of a soap bubble — 761
9	Literature — 763
9.0	Textbooks — 763
9.0.1	Photogrammetry — 763
9.0.2	Optic, camera and imaging techniques — 763
9.0.3	Digital image processing, computer vision and pattern recognition — 764
9.0.4	Mathematics and 3D computer graphics — 764
9.0.5	Least-squares adjustment and statistics — 764
9.0.6	Industrial, optical 3D metrology, quality control — 765
9.0.7	Applications — 765
9.1	Chapter 1 – Introduction and history — 765
9.2	Chapter 2 – Mathematical fundamentals — 767
9.2.1	Transformations and geometry — 767
9.2.2	Adjustment techniques — 767
9.3	Chapter 3 – Imaging technology — 768
9.3.1	Optics and sampling theory — 768
9.3.2	Camera modelling and calibration — 769
9.3.3	Sensors and cameras — 771
9.3.4	Target materials and illumination — 772
9.4	Chapter 4 – Analytical methods — 772
9.4.1	Analytical photogrammetry — 772
9.4.2	Bundle adjustment — 773
9.4.3	Multi-media photogrammetry — 774
9.4.4	Panoramic photogrammetry — 776
9.5	Chapter 5 – Digital image analysis — 776
9.5.1	Fundamentals — 776
9.5.2	Pattern recognition and image matching — 776
9.6	Chapter 6 – Measurement tasks and systems — 779

9.6.1	Target and reference systems —	779
9.6.2	Interactive measuring and processing systems —	780
9.6.3	Measurement of points and contours —	781
9.6.4	Laser-scanning systems —	781
9.6.5	Measurement of surfaces —	782
9.6.6	Range and 3D cameras —	782
9.6.7	Registration and orientation —	783
9.6.8	Dynamic and mobile systems —	783
9.7	Chapter 7 – Quality issues and optimization —	784
9.7.1	Project planning and simulation —	784
9.7.2	Quality —	785
9.7.3	Camera calibration —	786
9.8	Chapter 8 – Applications —	787
9.8.1	Architecture, archaeology, city models —	787
9.8.2	Engineering and industrial applications —	789
9.8.3	Underwater photogrammetry —	790
9.8.4	Medicine, forensics, earth sciences —	791
9.9	Other sources of information —	792
9.9.1	Standards and guidelines —	792
9.9.2	Working groups and conferences —	792

Abbreviations — 795

Image sources — 799

Index — 803