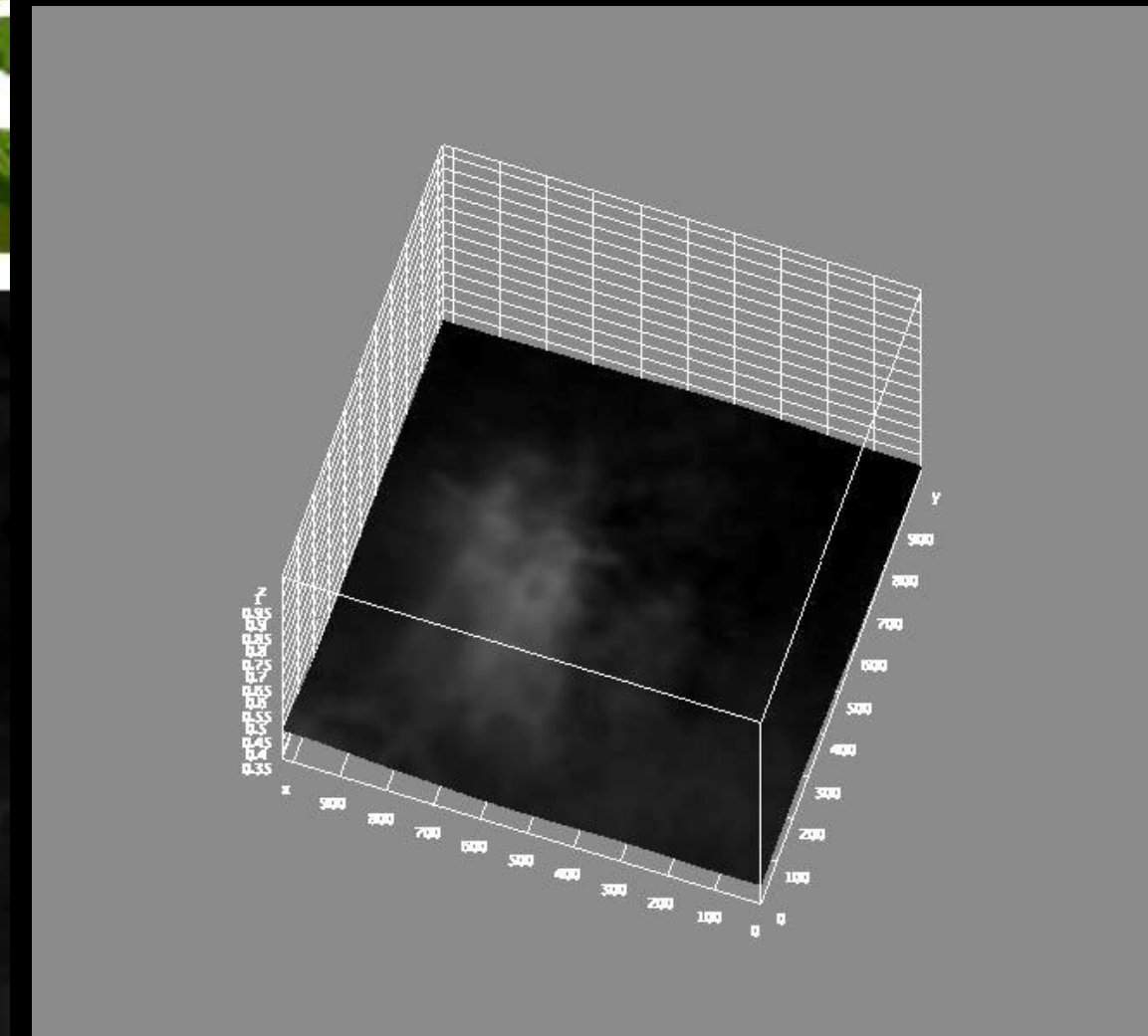
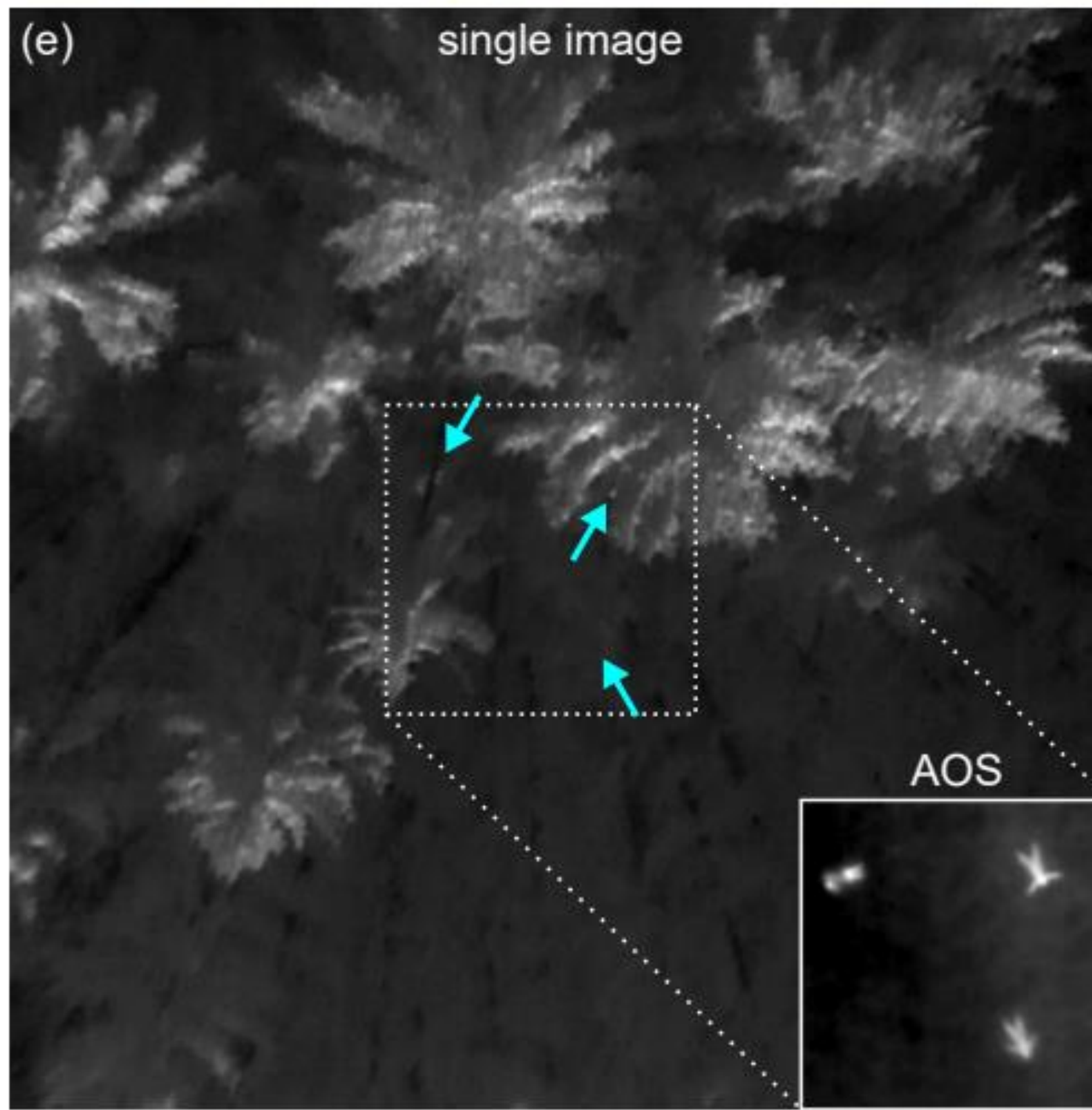
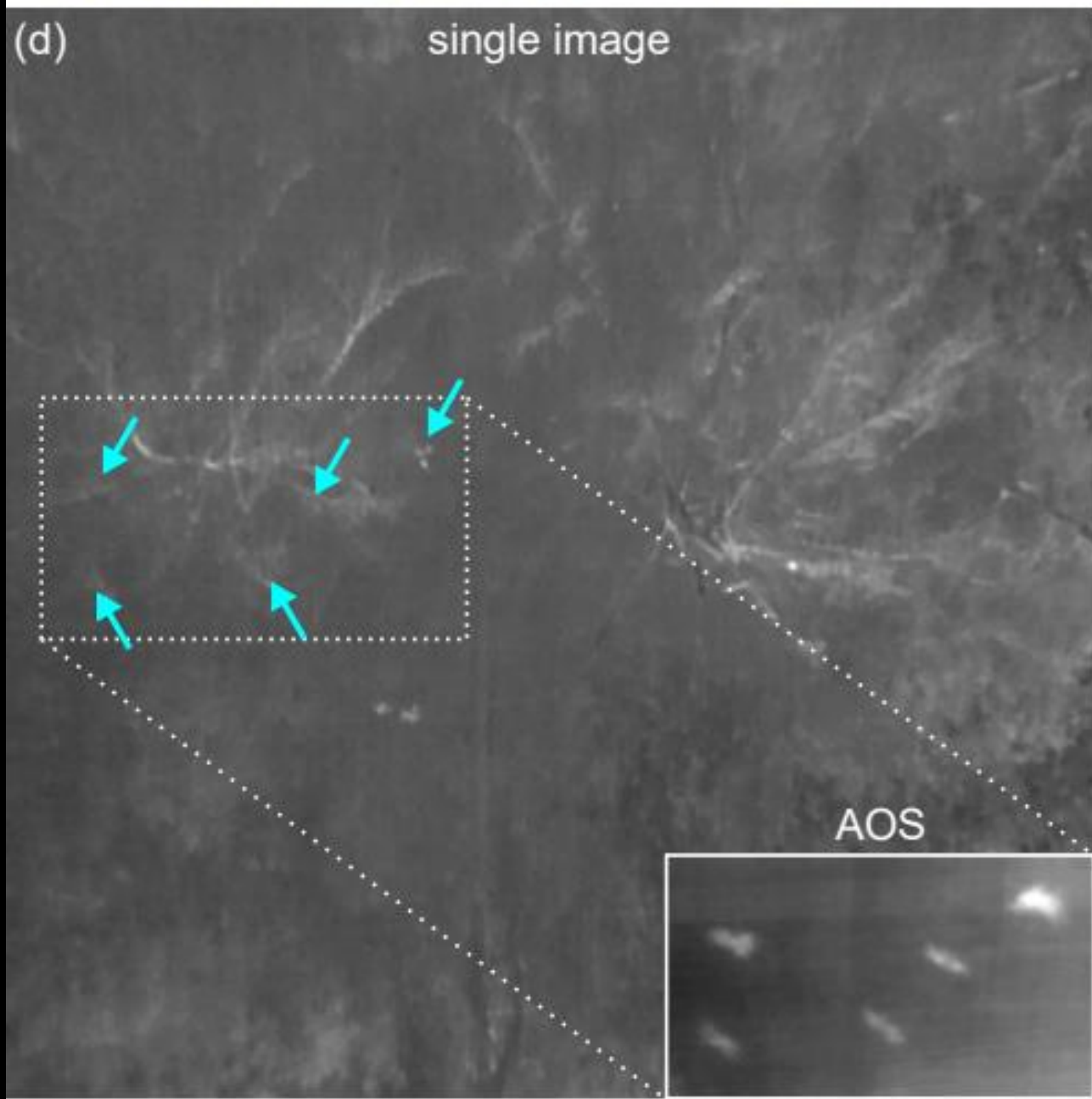
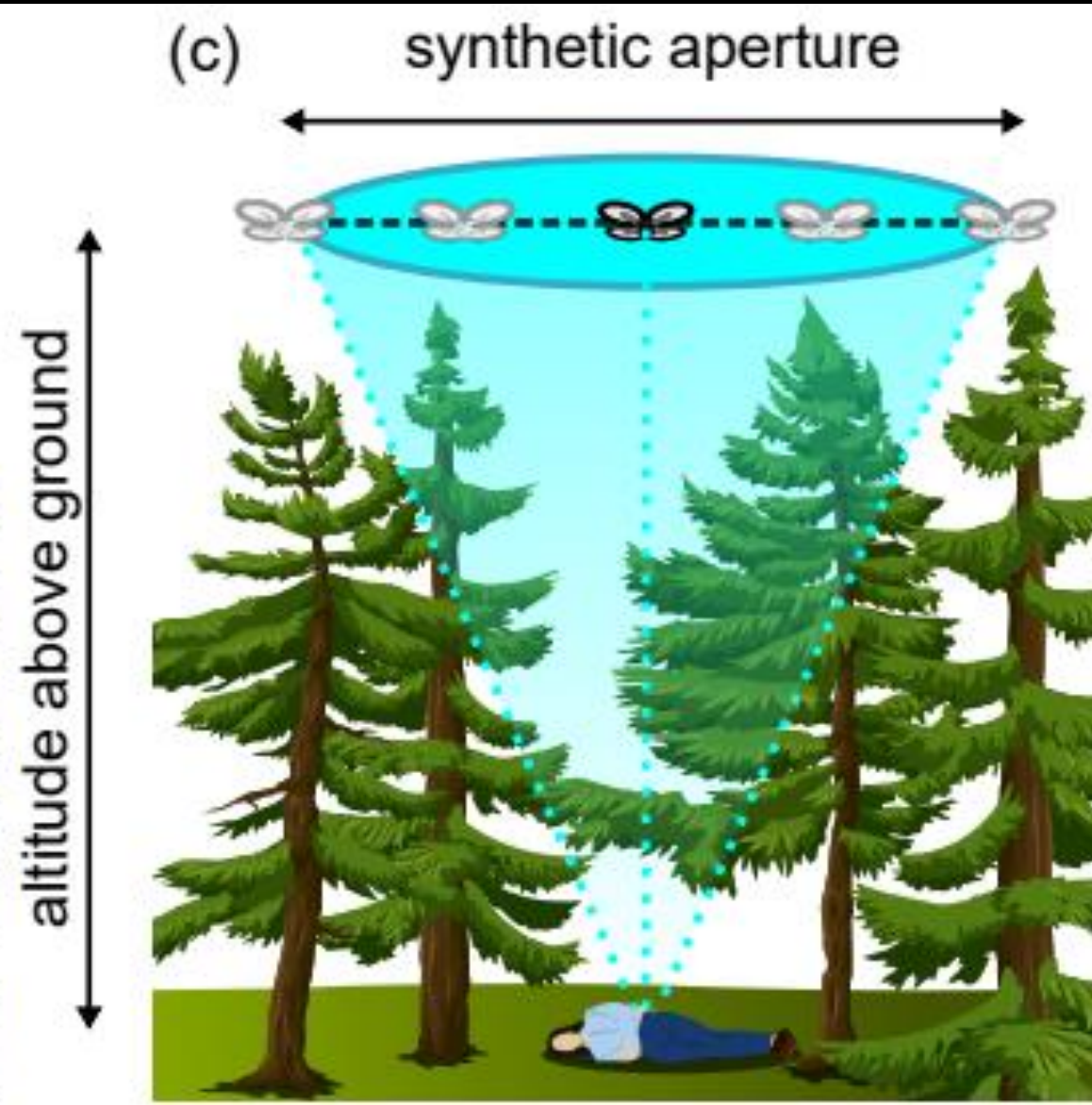
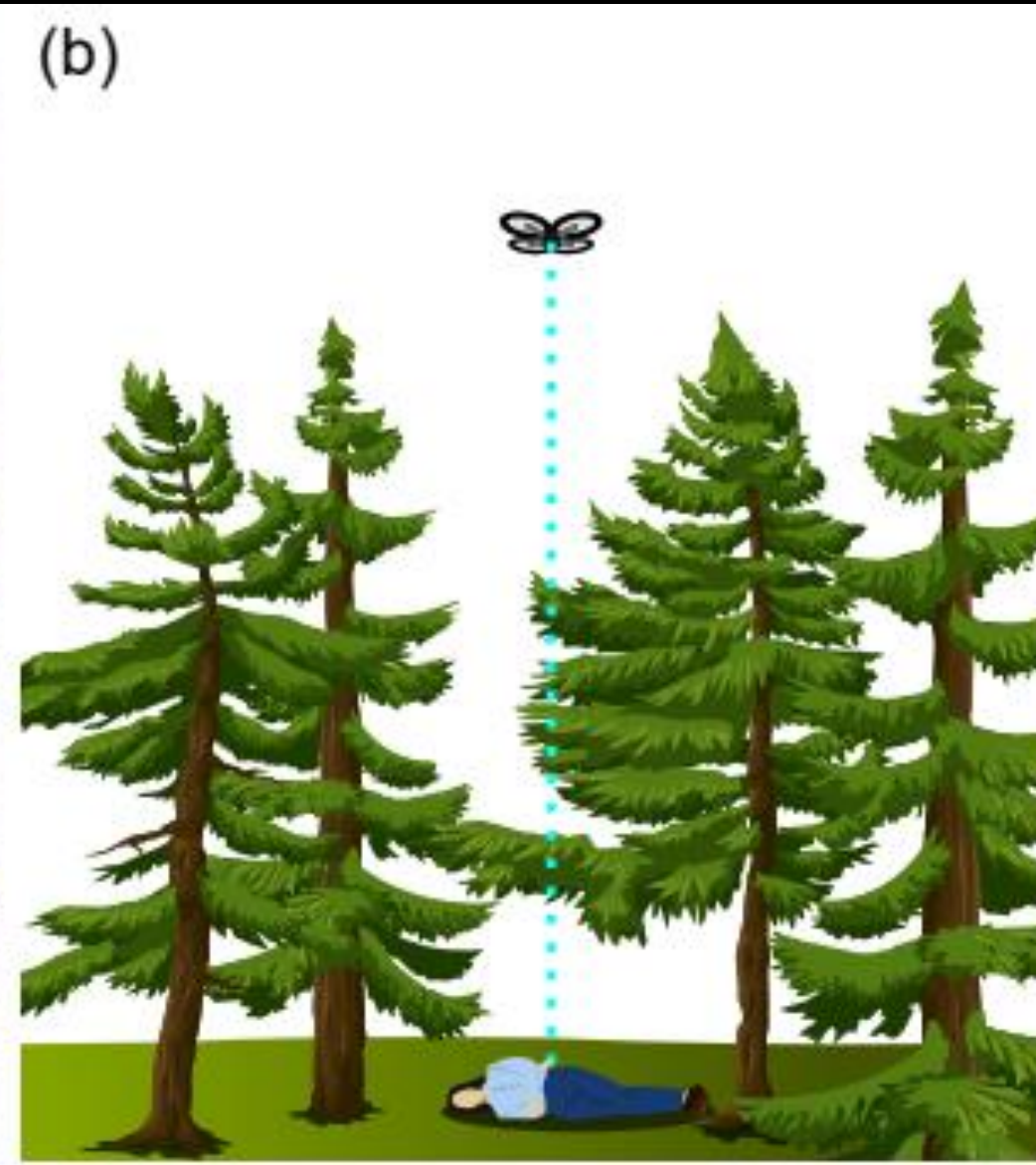
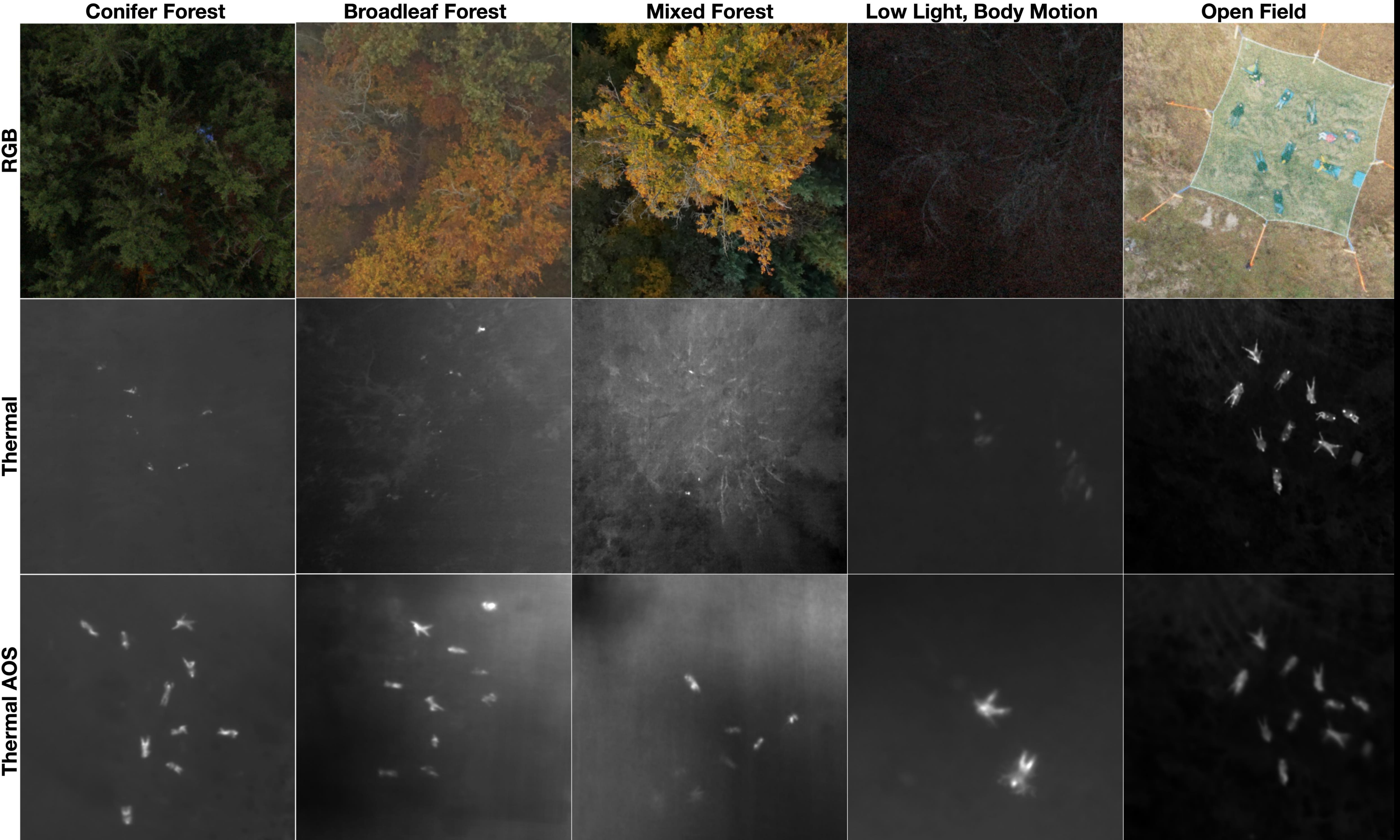


Airborne Optical Sectioning for Nesting Observation, Nature SciRep, 2020

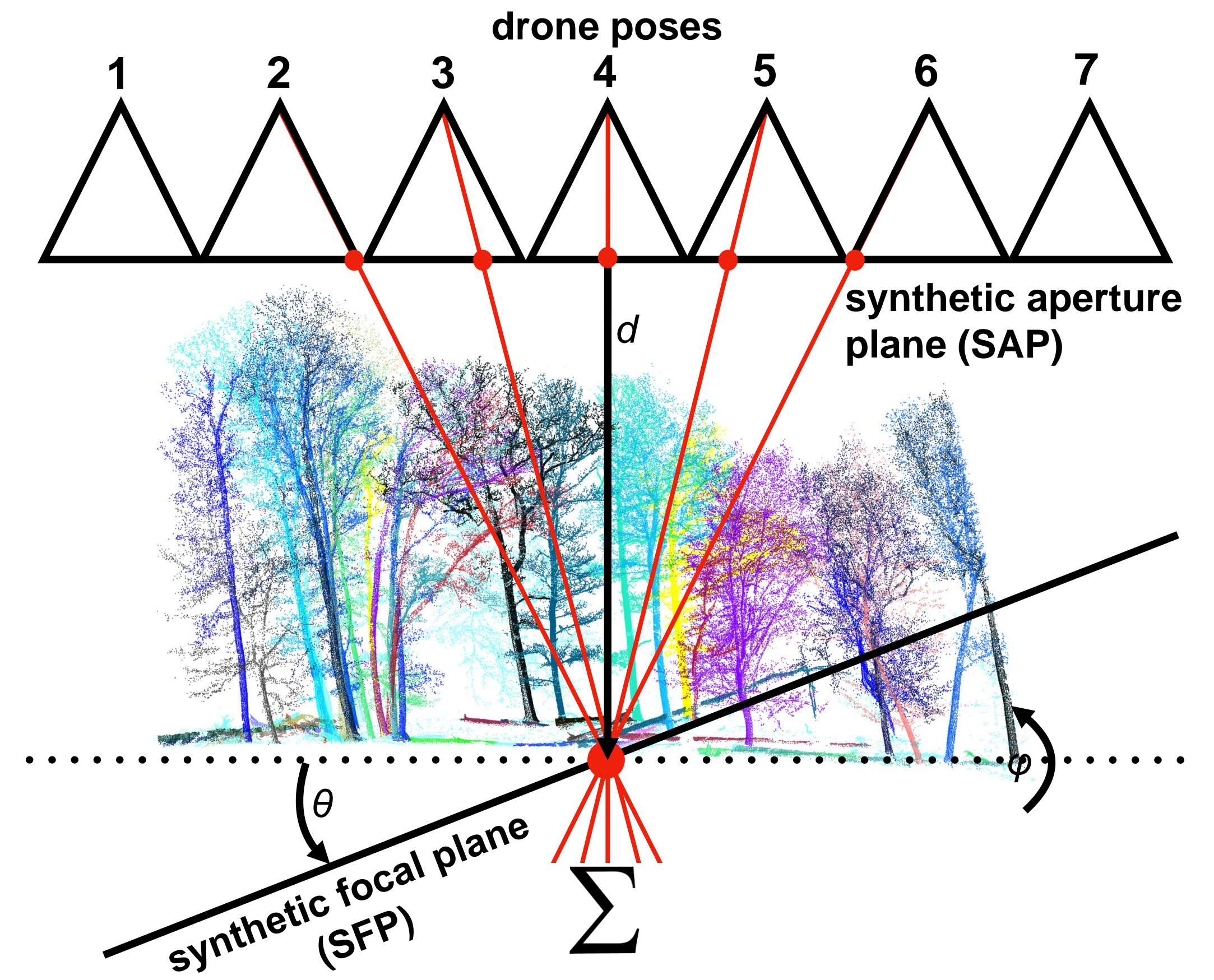
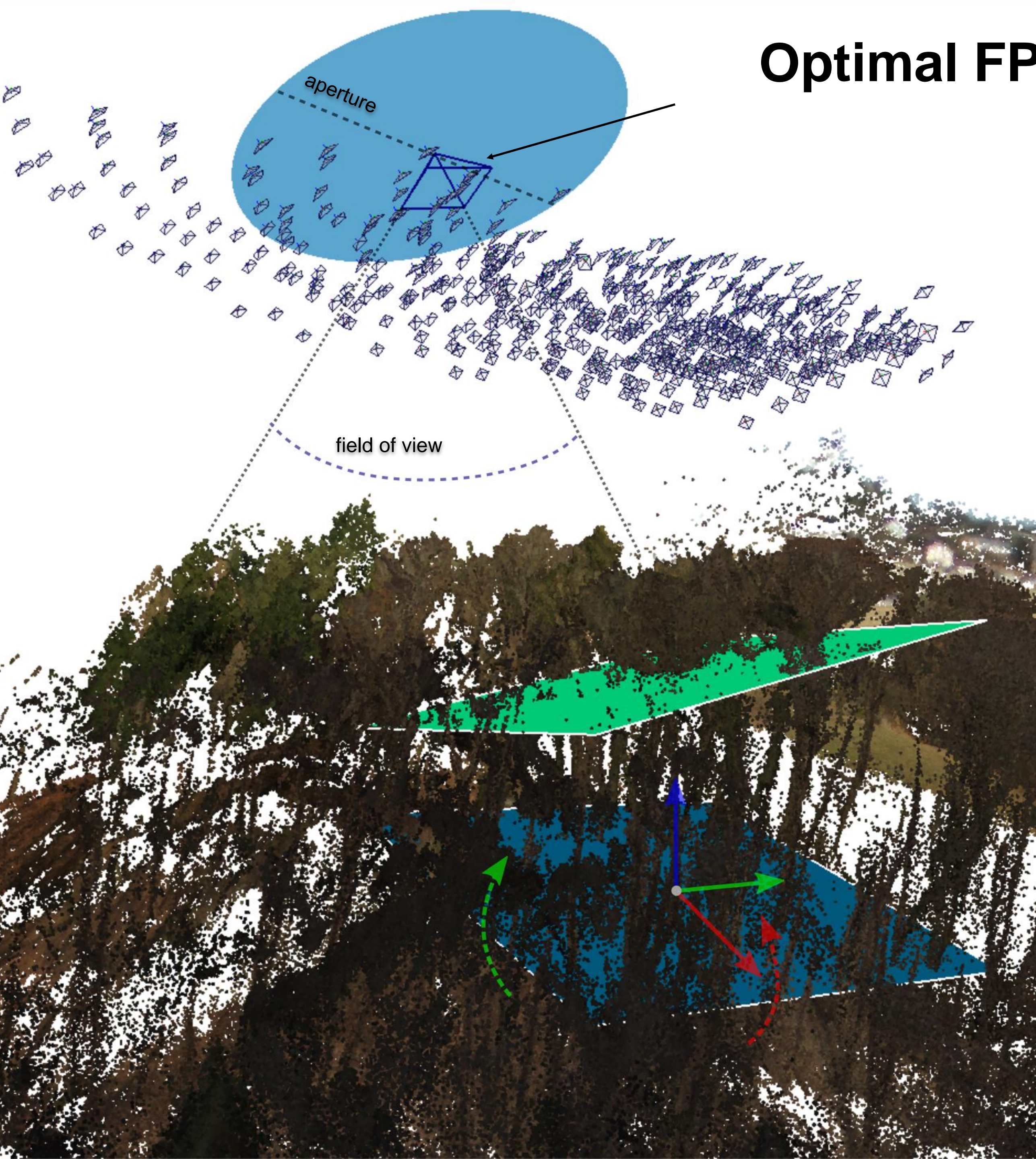
Search and Rescue by Airborne Optical Sectioning (SARAOS)





Fast Automatic Visibility Optimization for Thermal Synthetic Aperture Visualization, IEEE Geoscience and Remote Sensing, 2020

Optimal FP parameters - automatic and fast?



4 Scenes

Iterations for
Gray-Level Variance Metric
using Sequential
Quadratic Programming

(Realtime)

Parameters Bounded to
d being 22 to 38 m away
and θ, φ being $\pm 10^\circ$ off
from the Synthetic
Aperture Plane

Conifer Forest (iteration: 1)



Broadleaf Forest (iteration: 1)

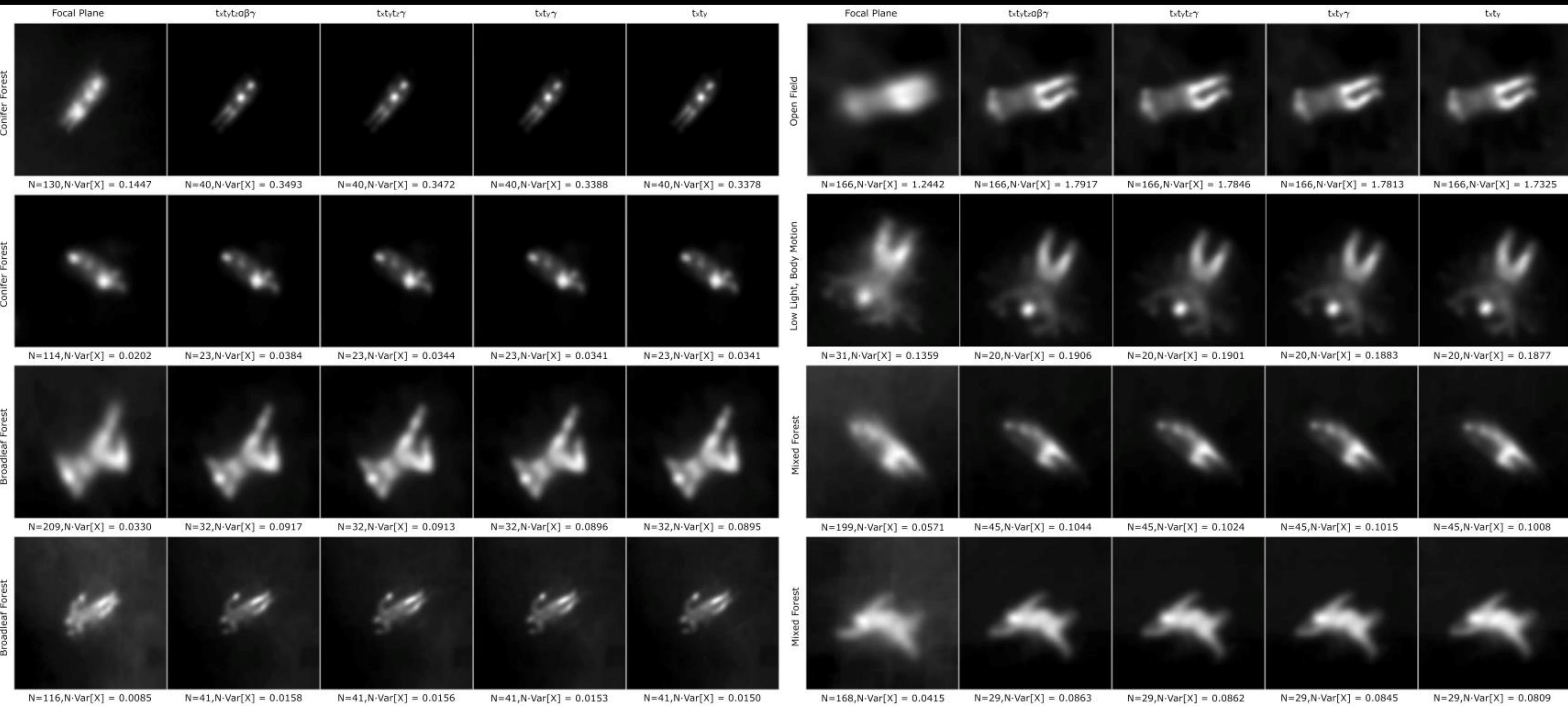


Mixed Forest (iteration: 1)



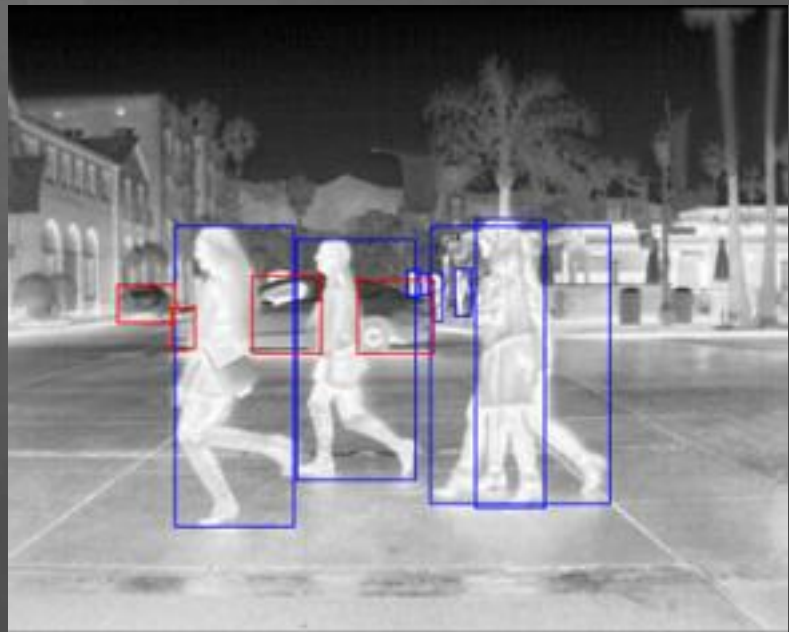
Low Light, Body Motion (iteration: 1)



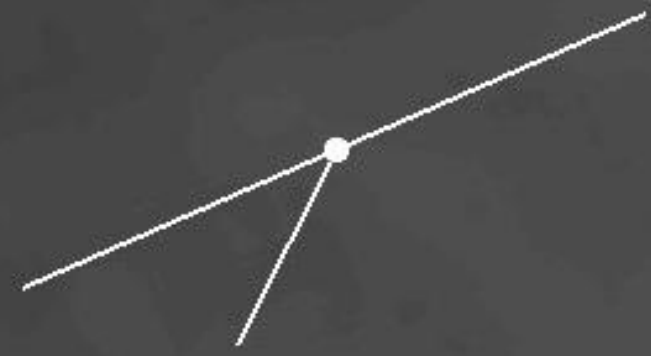


Pose Error Reduction for Focus Enhancement in Thermal Synthetic Aperture Visualization, IEEE Geoscience and Remote Sensing Letters, 2020 (submitted)

Search and Rescue by Airborne Optical Sectioning (SARAOS)



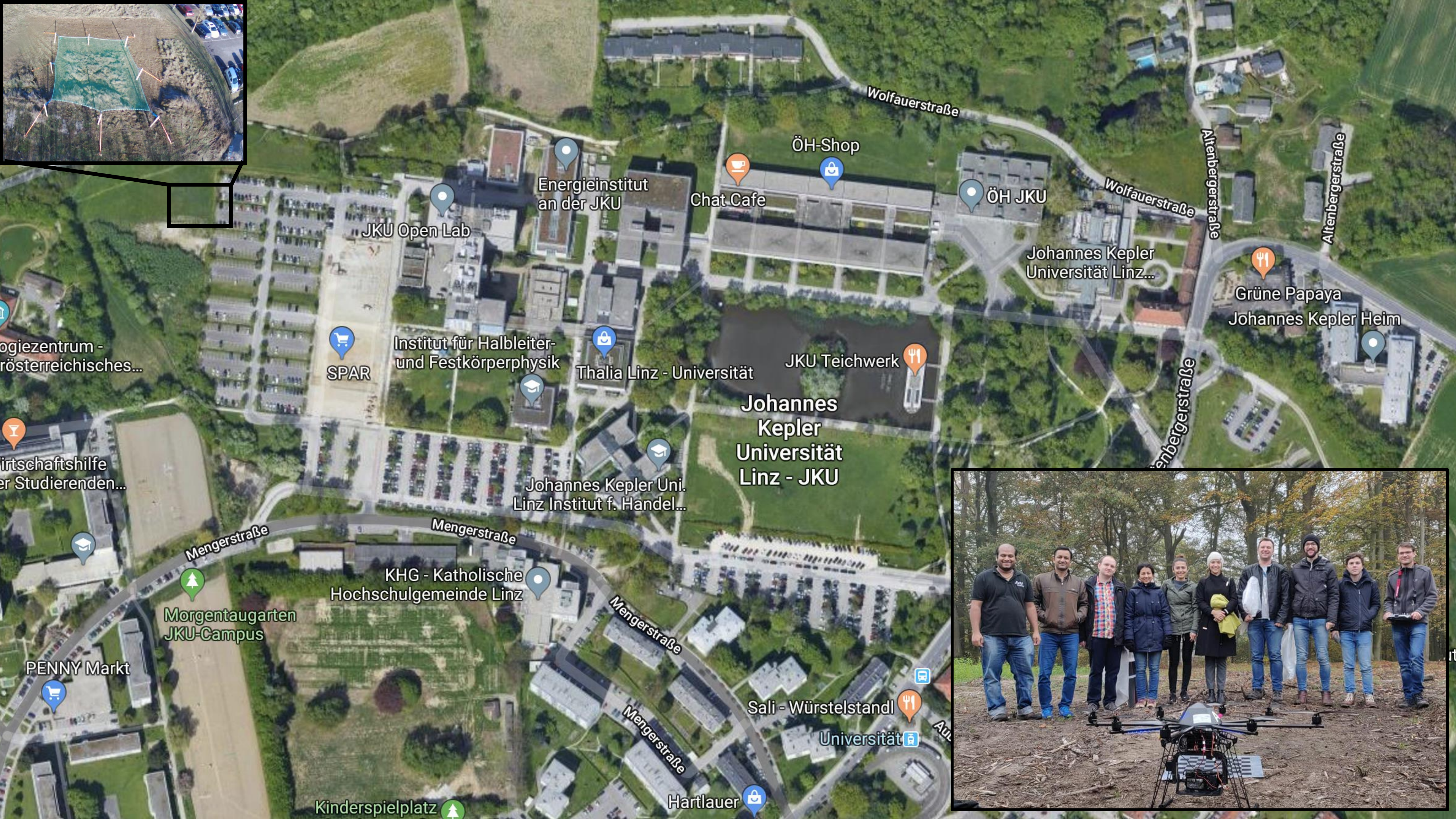
FLIR thermal dataset



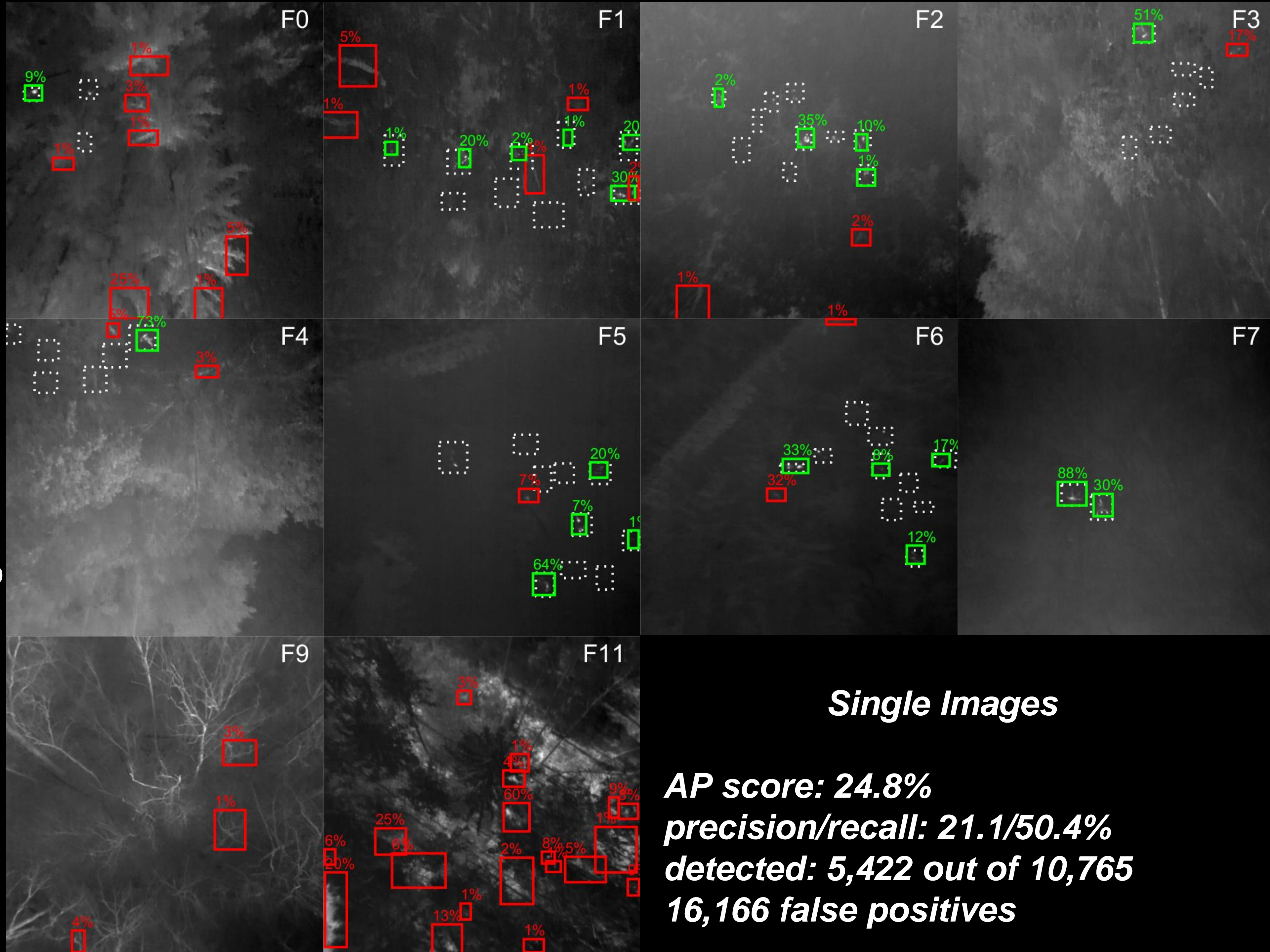
occlusion (forest)



no occlusion (open field)



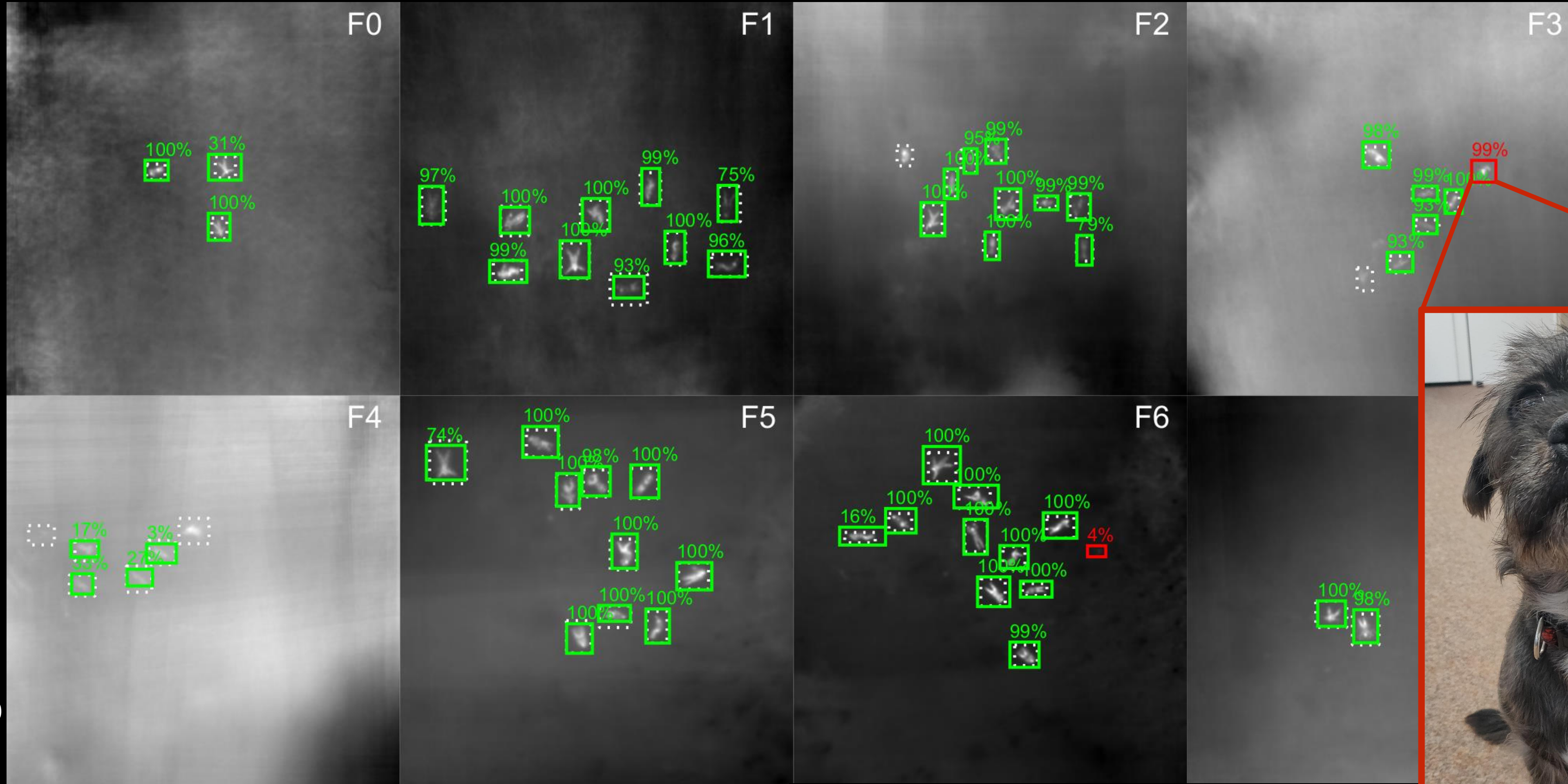
**Search and Rescue with Airborne Optical Sectioning,
Nature Machine Intelligence 2020**



Single Images

AP score: 24.8%
precision/recall: 21.1/50.4%
detected: 5,422 out of 10,765
16,166 false positives

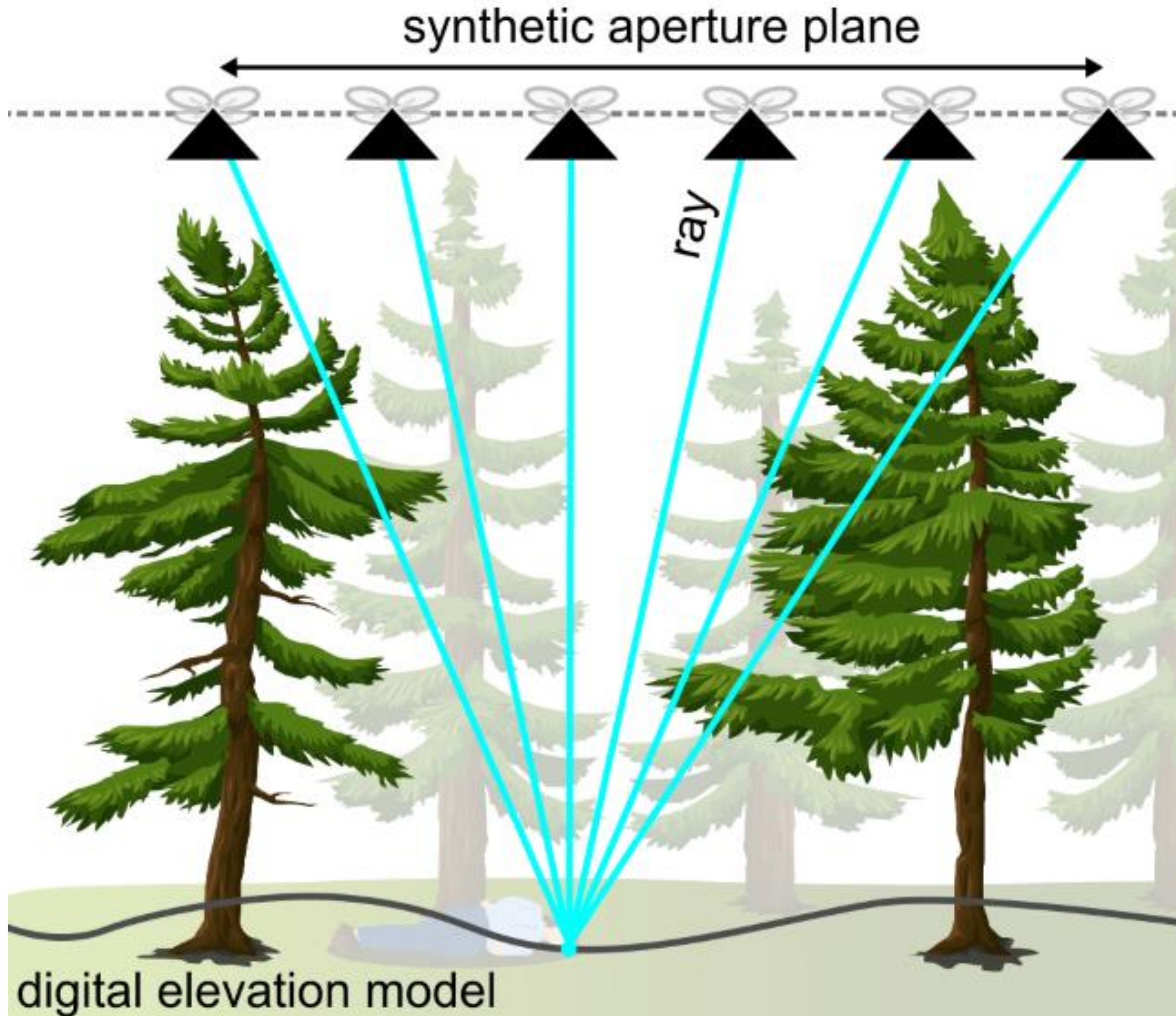
**Search and Rescue with Airborne Optical Sectioning,
Nature Machine Intelligence 2020**



AOS Integral Images

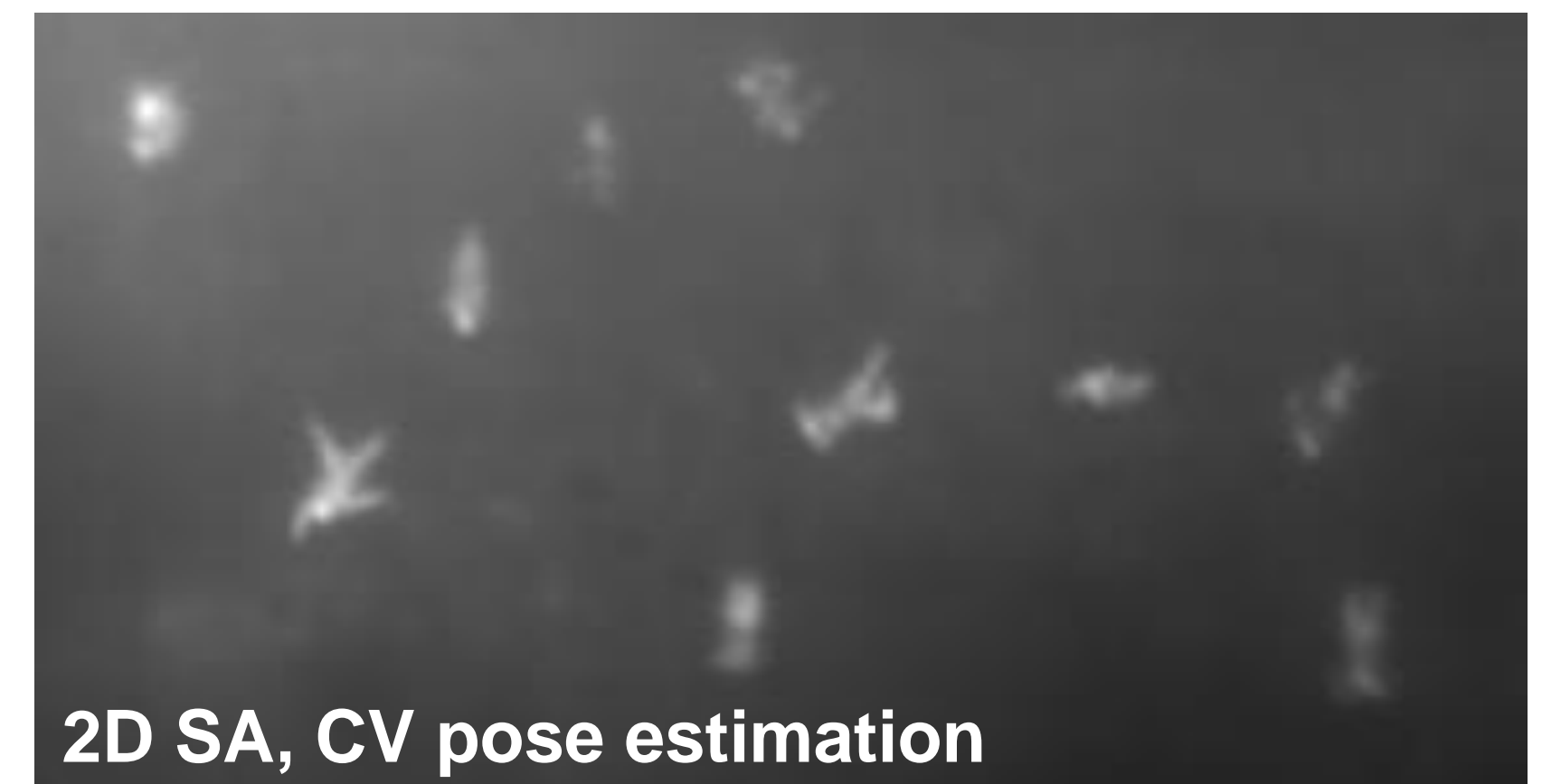
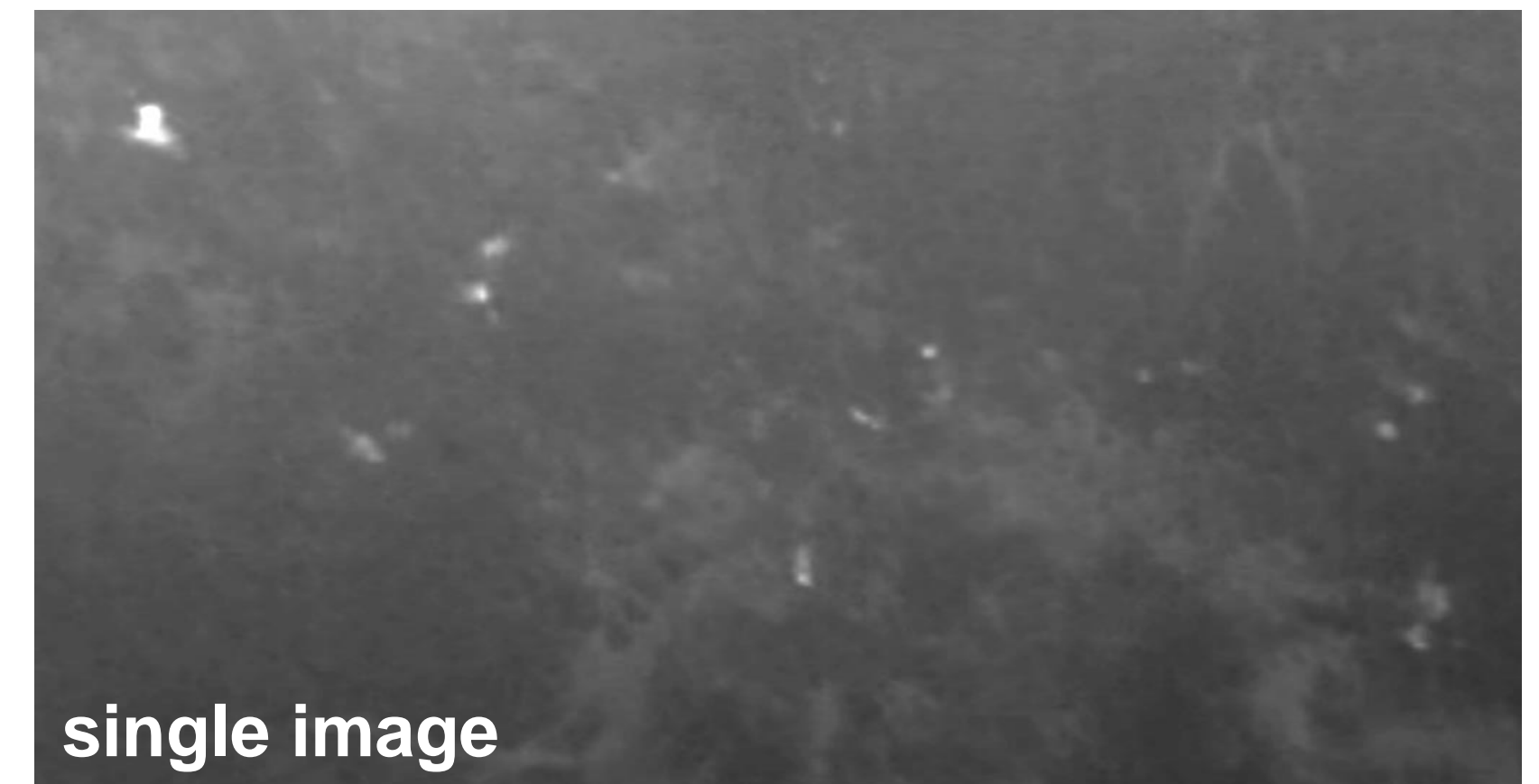
AP score: 92.2%
precision/recall: 96.4/93%
detected: 53 out of 57
2 false positives (branches and a dog)

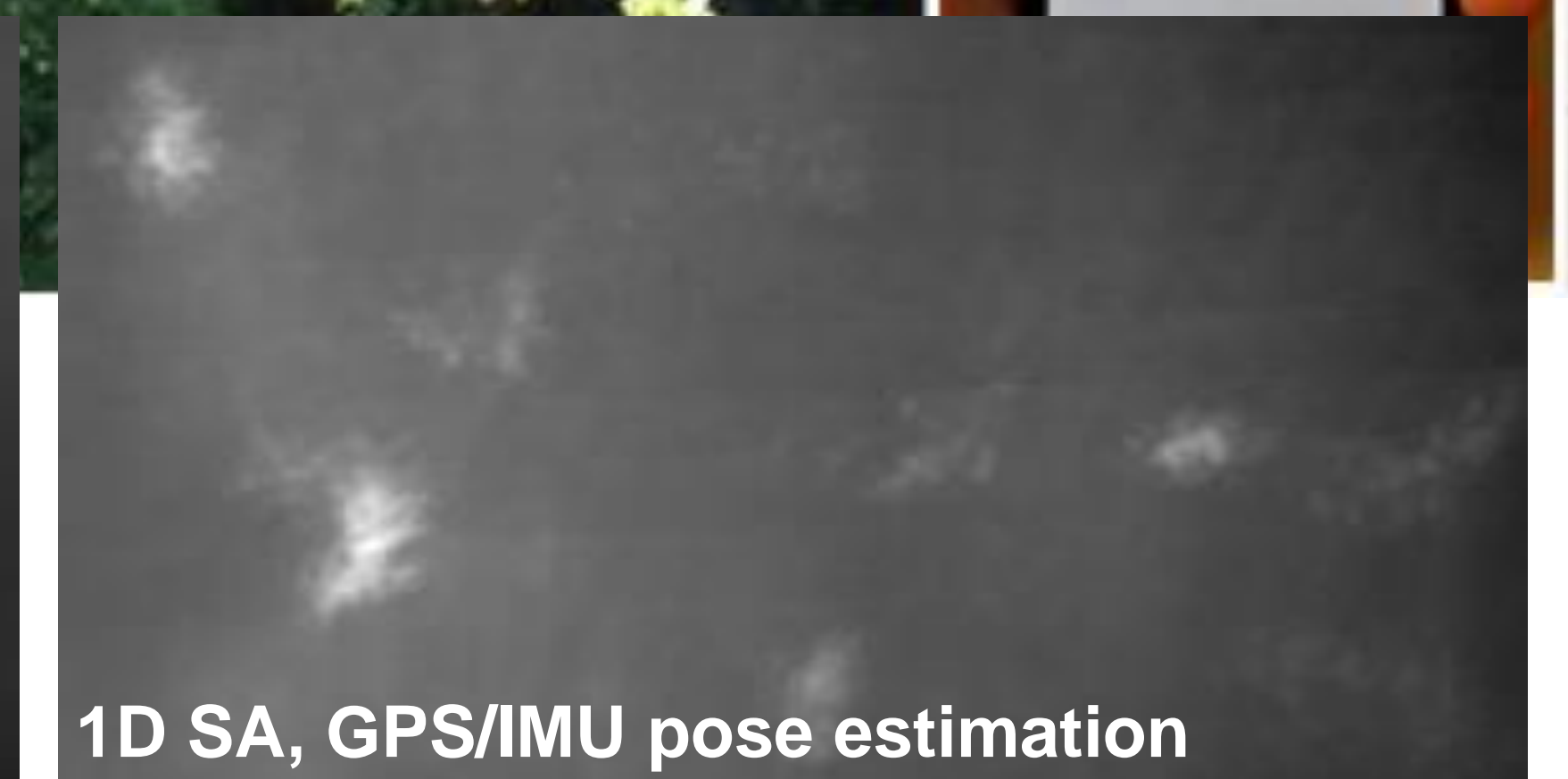
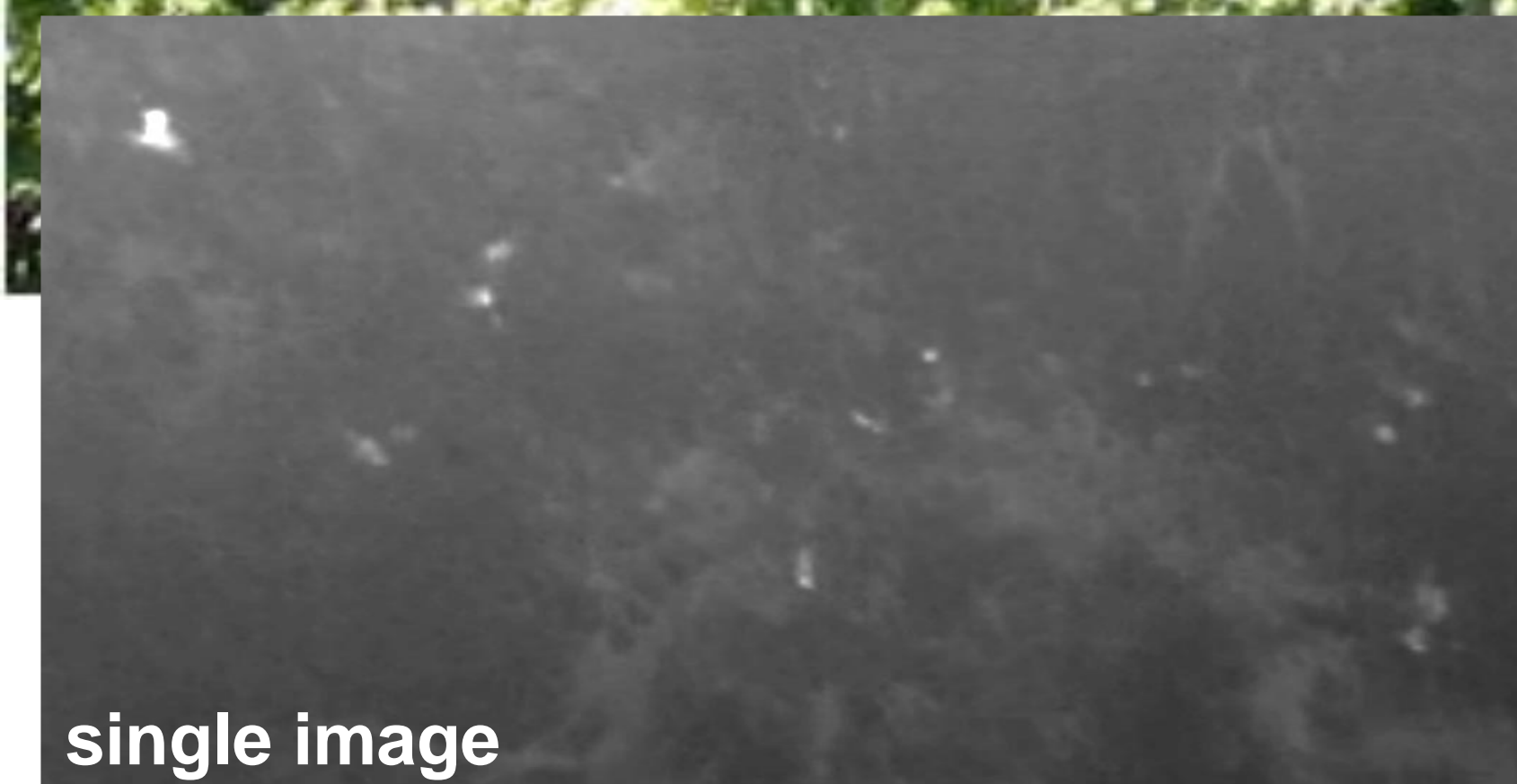
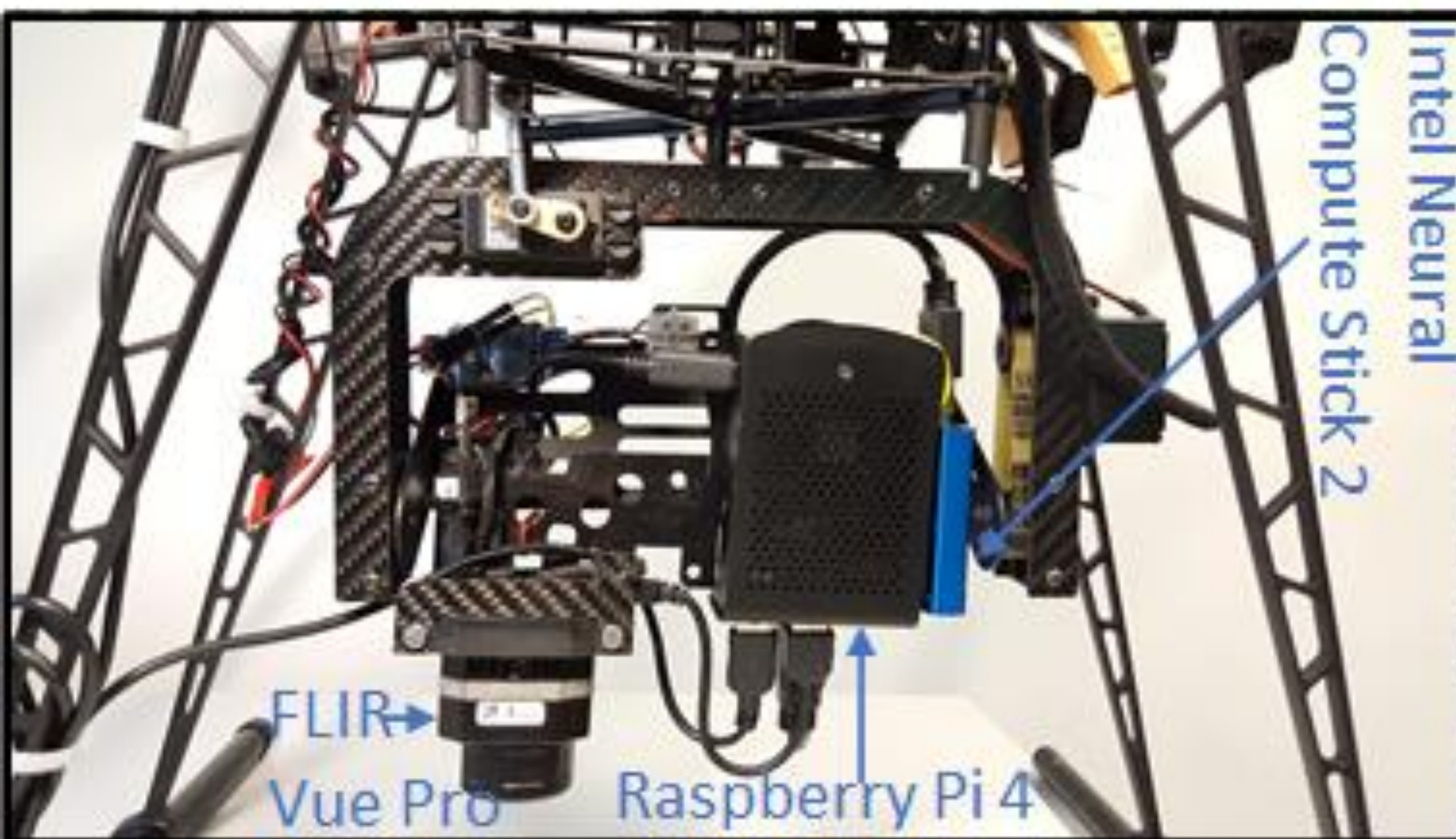
Real-Time



To get this running fast on the drone and during flight:

- short linear (1D) apertures
- GPS/IMU-based pose estimation
- digital elevation model to compute integral image for focal surface and drone control on Raspberry Pi
- classification with YOLO4-tiny on Intel Neural Compute Stick
- training set = test set of the previous study

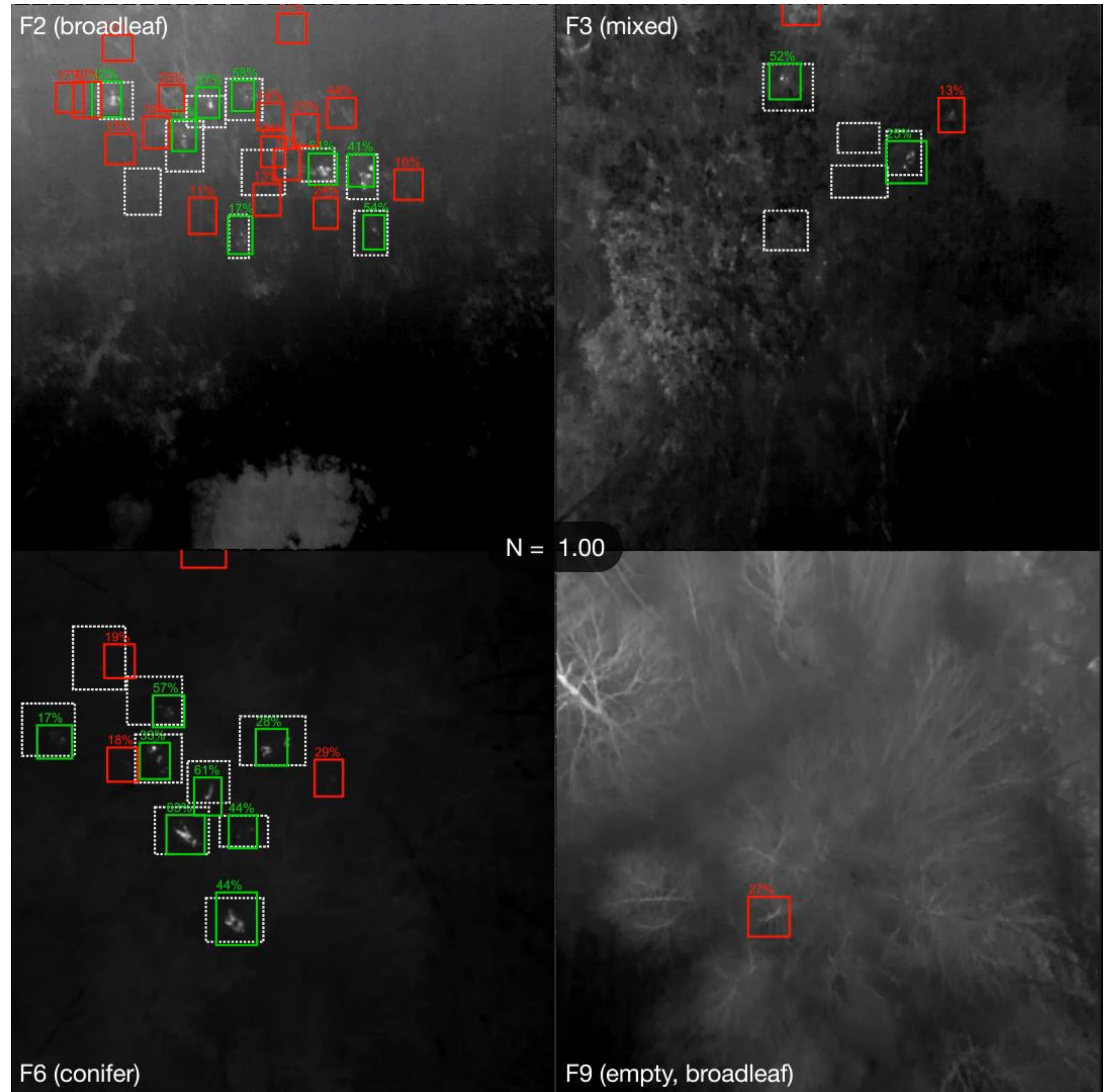
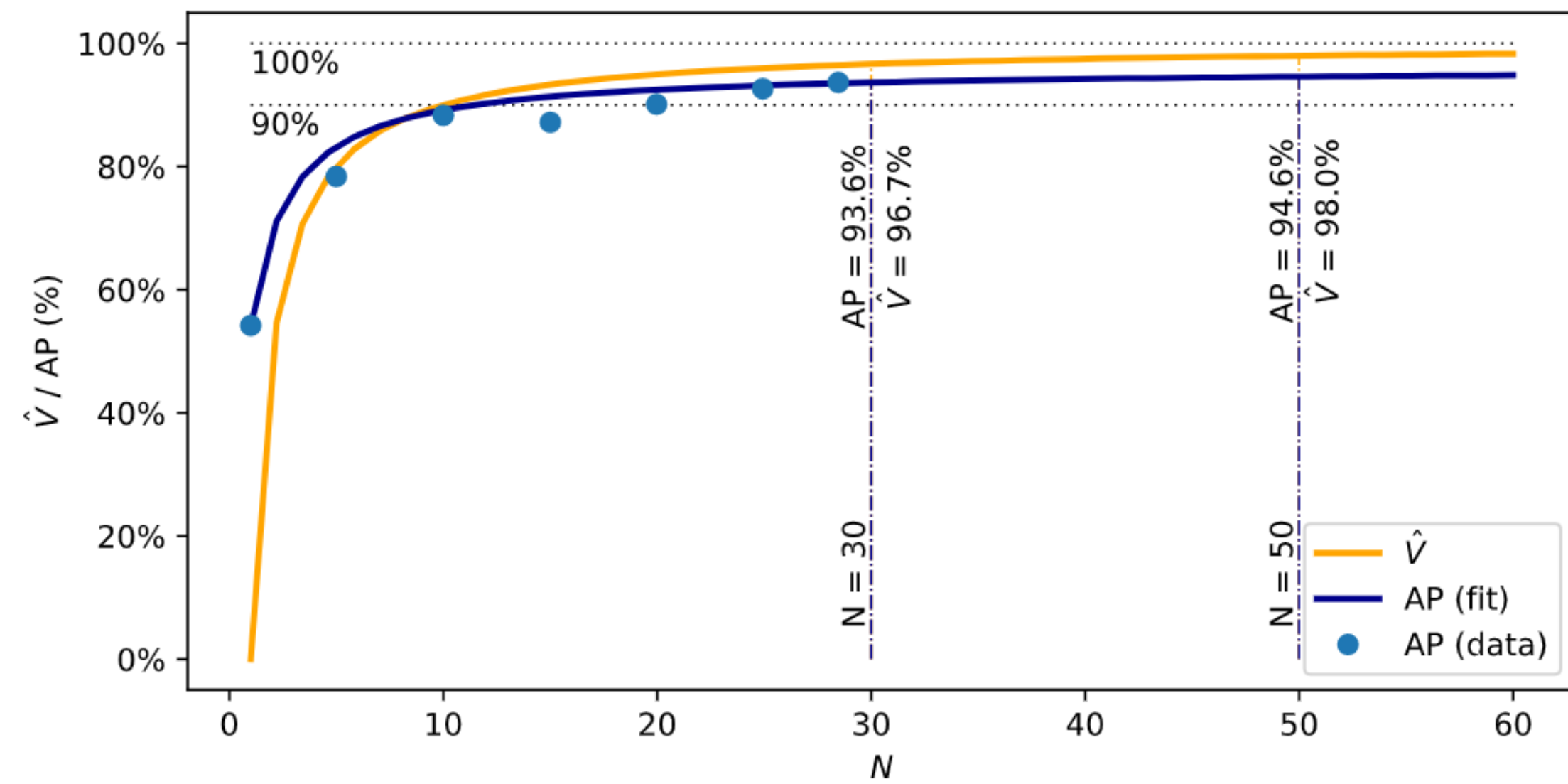




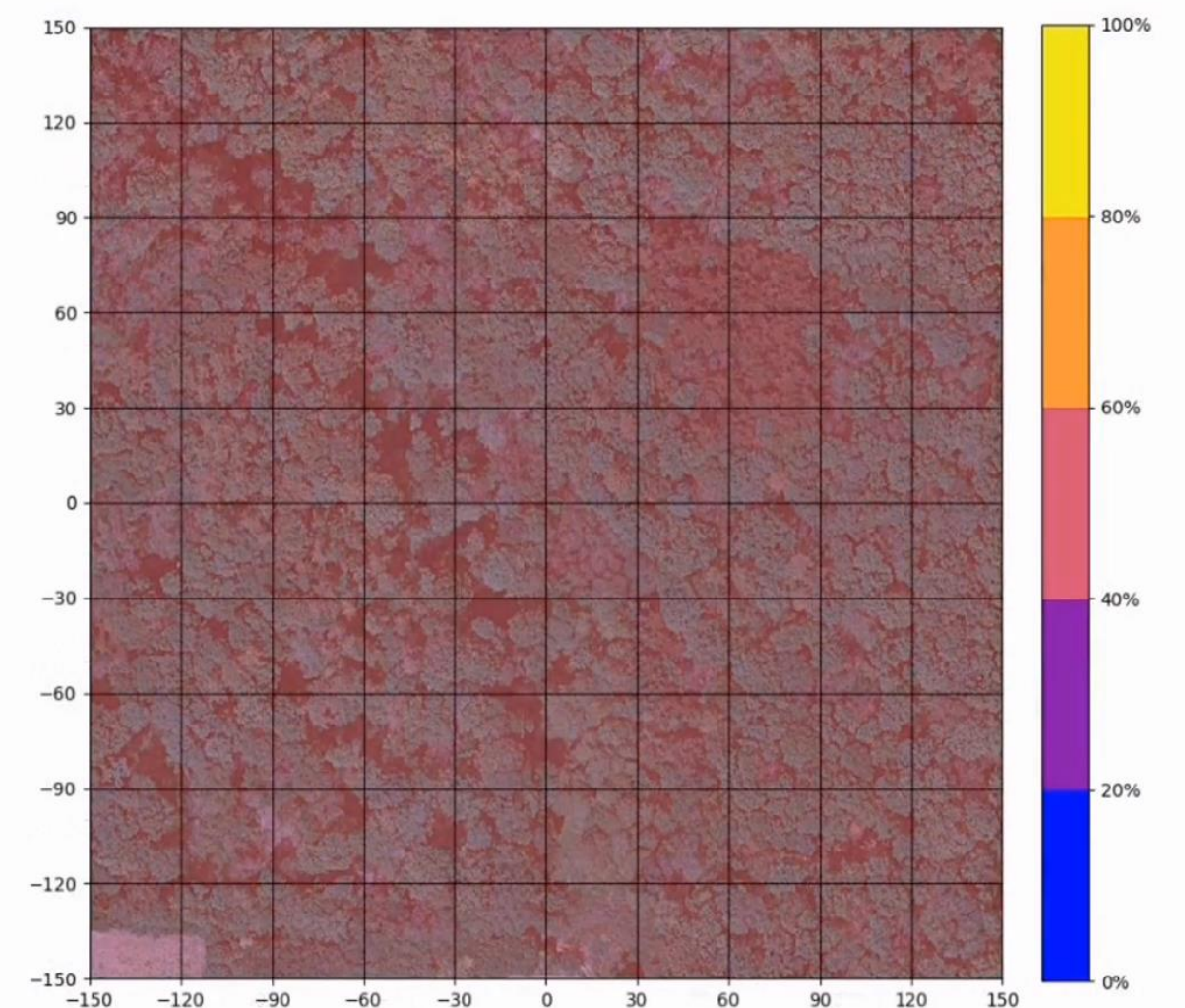
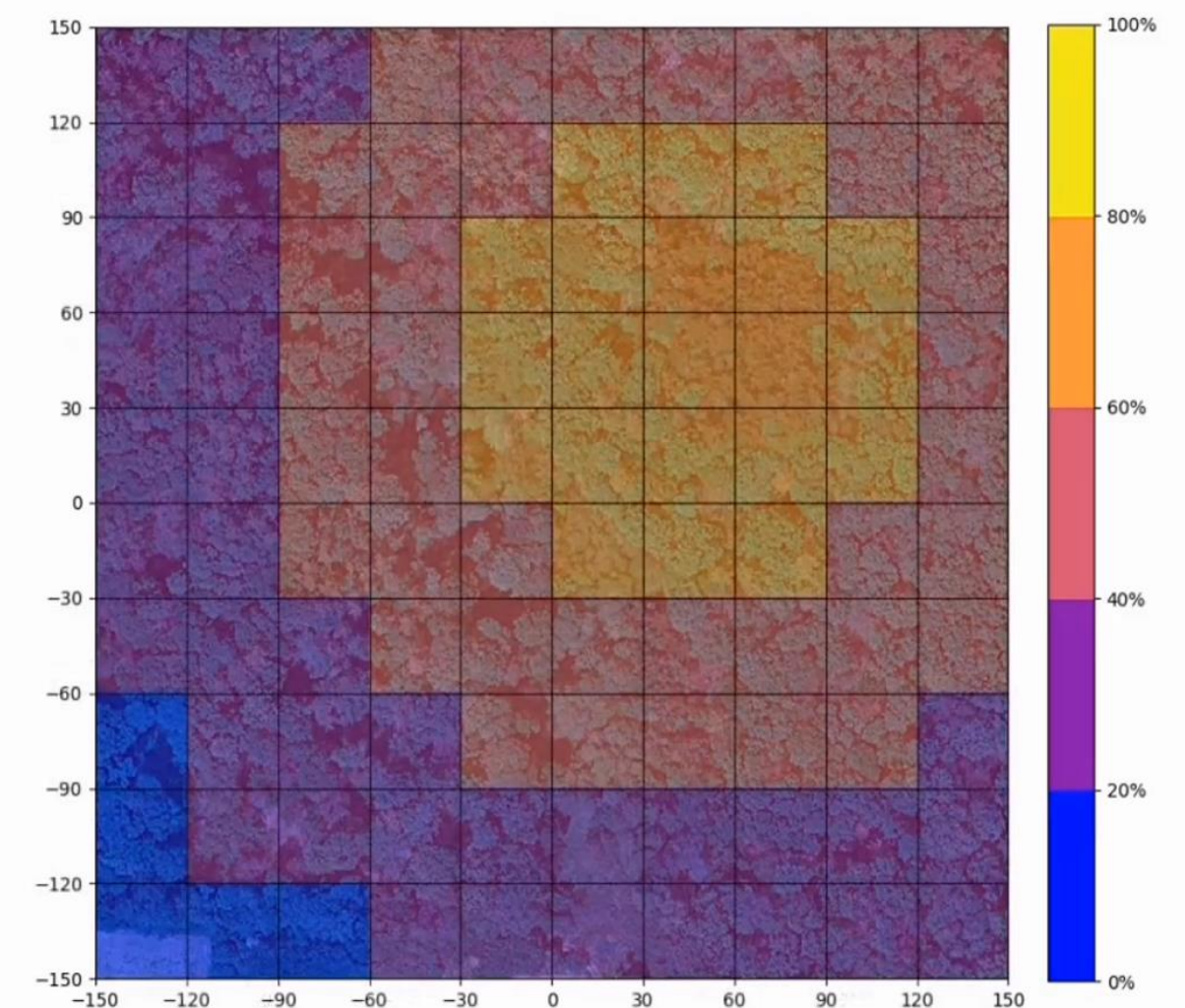
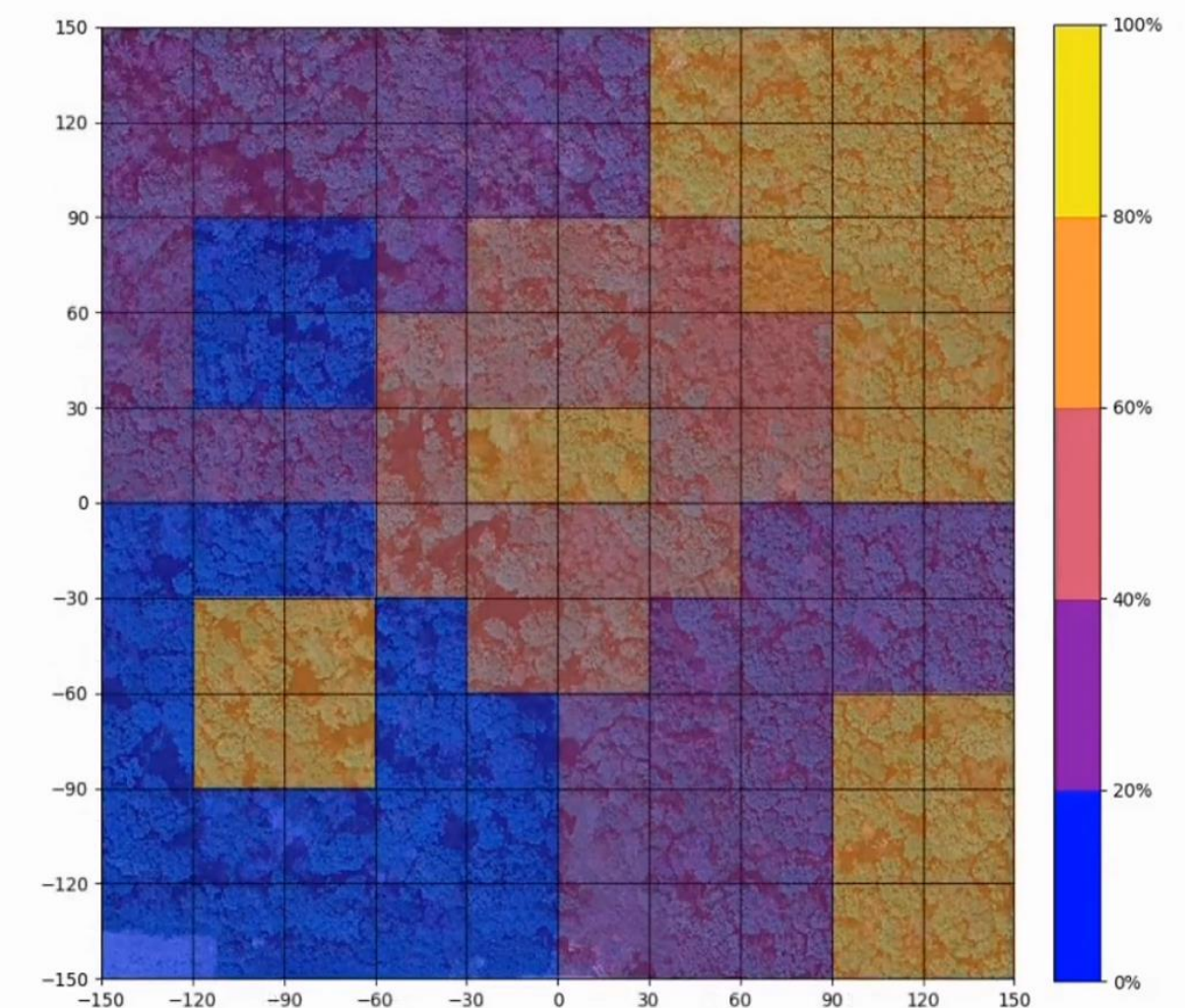
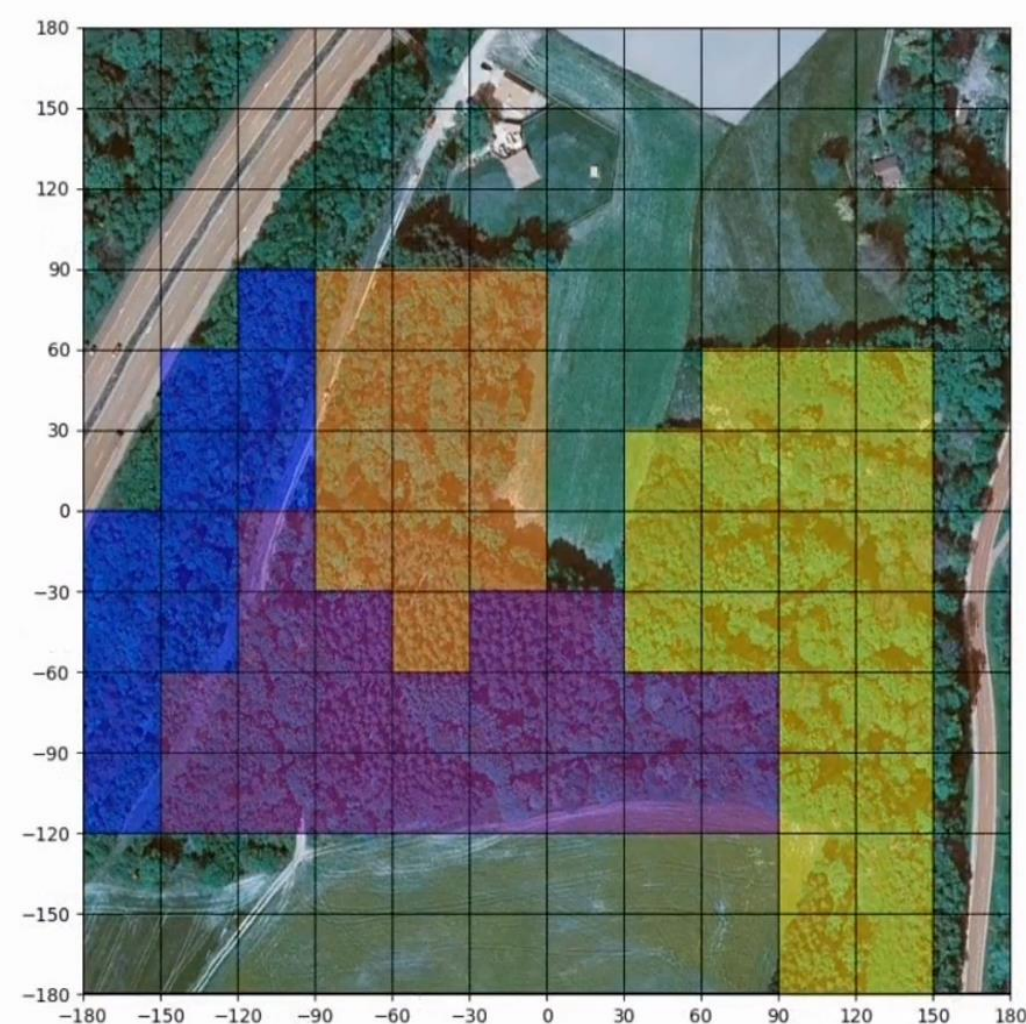
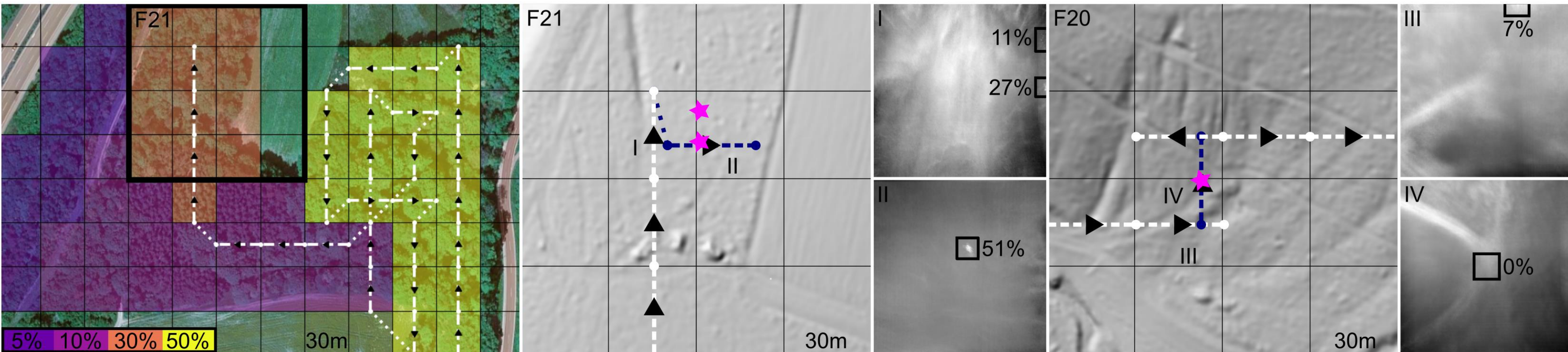




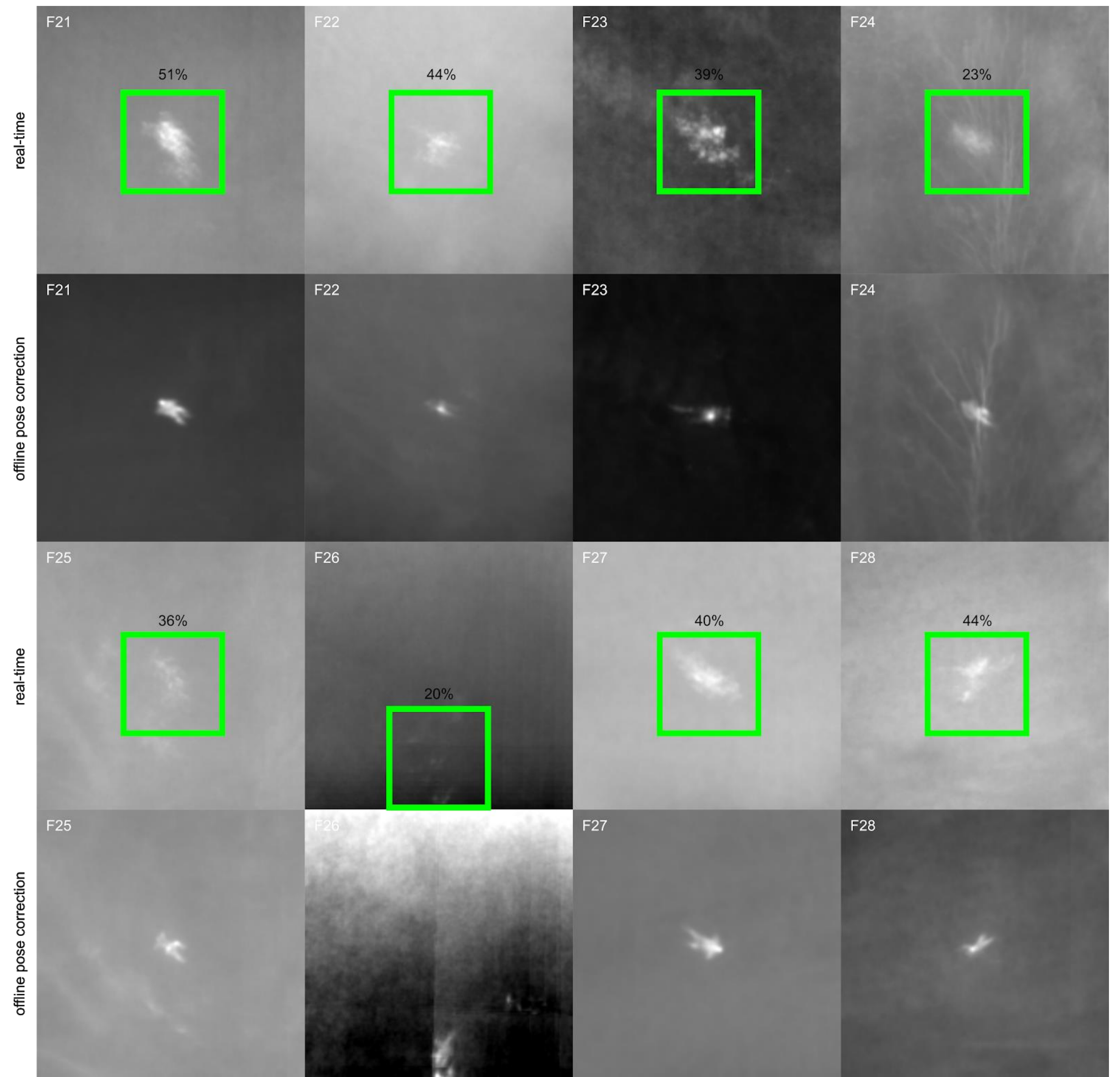
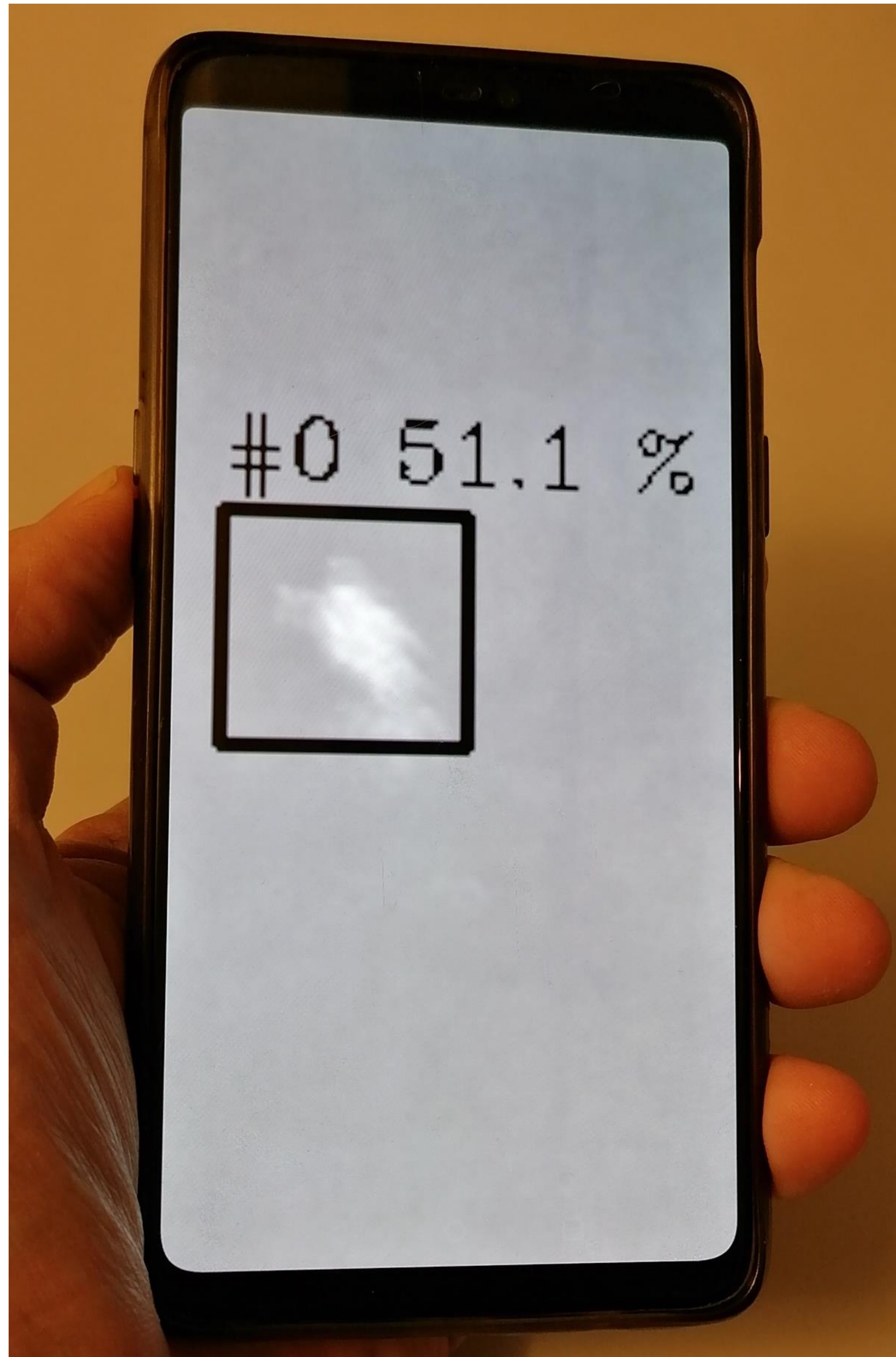
1D Synthetic Aperture



Adaptive Path Planning



Visual Enhancement



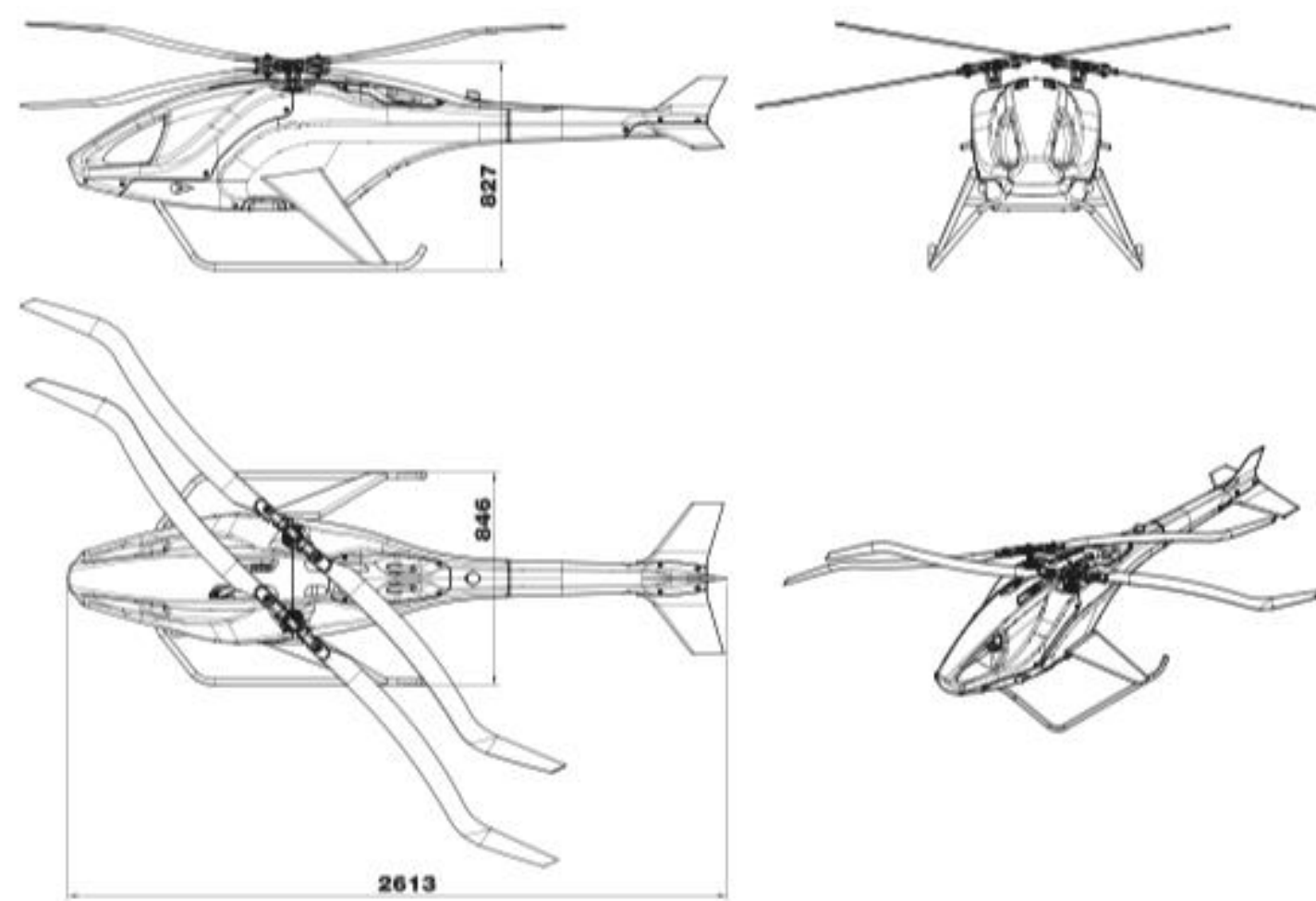
What's next?

- better unmanned aircraft (several-hundred km range) and cooperation with manufacturer
- possible integration into manned aircrafts (helicopters)
- trial missions with rescue teams (ÖAMTC, police, Bundesheer)
- more training data, better classifiers, improved occlusion removal
- autonomous path-planning (on the fly)
- ...

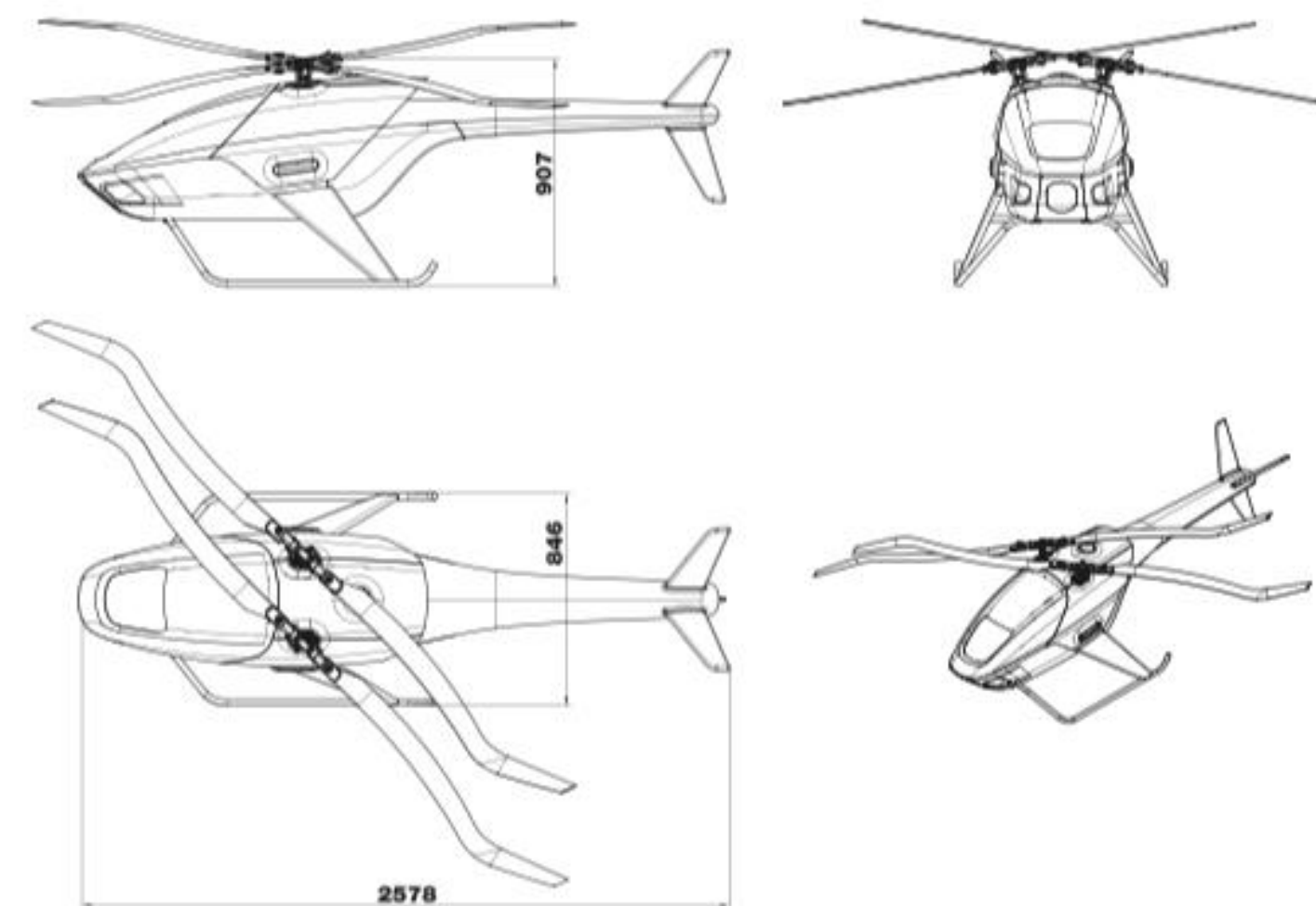


Endurance

STR - 35



STR - 50



specs

Engine	Length	Width	Rotor height
Boxer *	2600 mm	850 mm	830 mm
12 kw			
Rotor diameter	Endurance		
2950 mm	3. h **		
Weight (Empty)	Max. take off weight		
75 kg ***	150 kg		

specs

Engine	Length	Width	Rotor height
Wankel *	2600 mm	850 mm	910 mm
15 - 25 kw			
Rotor diameter	Endurance		
2950 mm	6. h **		
Weight (Empty)	Max. take off weight		
80 kg ***	150 kg		



* also available with an electric motor 12 KW

** depending on payload and flight profile / Electric up to 1,5 h

*** electric + 40 kg for battery

* also available with an electric motor 12 KW

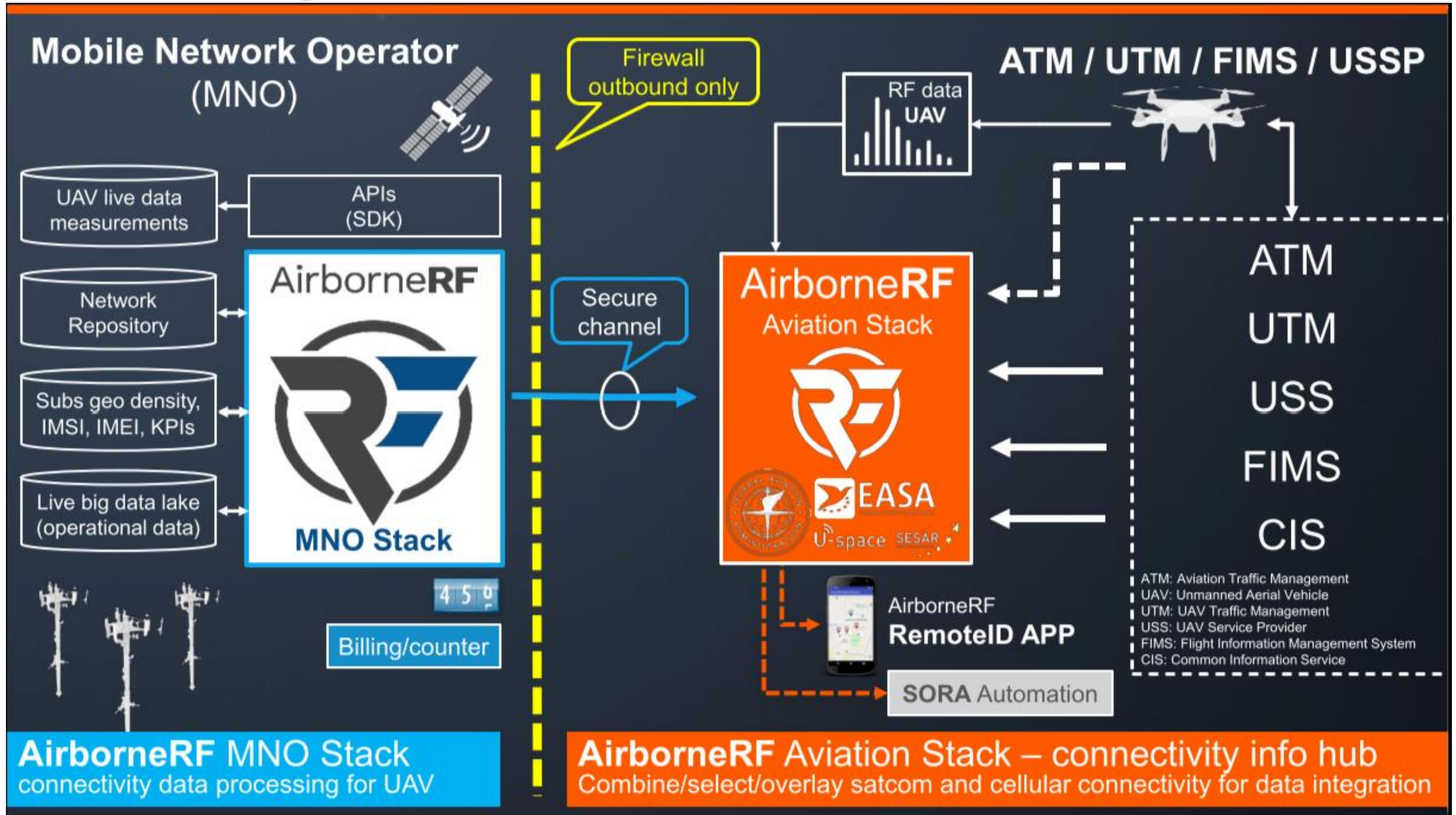
** depending on payload and flight profile / Electric up to 1,5 h

*** electric + 40 kg for battery

Rega



Connectivity





Thank you!

www.jku.at/cg