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(54) **SYSTEM AND METHOD FOR STRUCTURAL INSPECTION AND CONSTRUCTION ESTIMATION USING AN UNMANNED AERIAL VEHICLE**

(71) Applicant: **EZ3D, LLC**, Louisville, CO (US)

(72) Inventors: **Martin Marra**, Louisville, CO (US);
James F. Smyth, Richmond, VA (US)

(73) Assignee: **EZ3D, LLC**, Louisville, CO (US)

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Primary Examiner — Sathyanaraya V Perungavoor

Assistant Examiner — Howard D Brown, Jr.

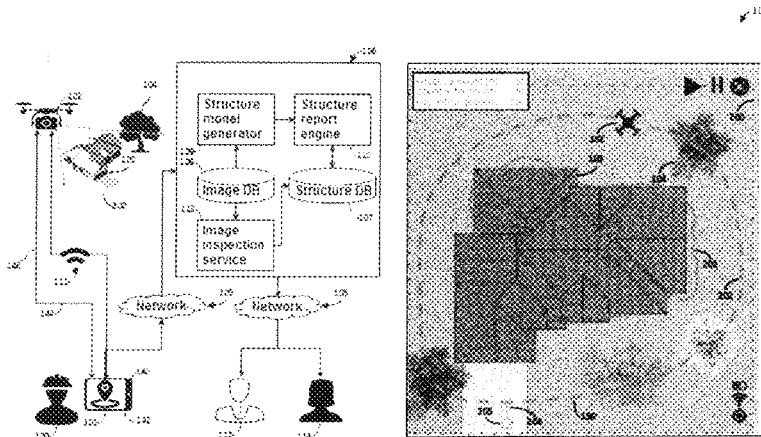
(74) *Attorney, Agent, or Firm* — Lewis Brisbois Bisgaard & Smith LLP; Ian R. Rainey

(57) **ABSTRACT**

An automated image capturing and processing system and method may allow a field user to operate a UAV via a mobile computing device to capture images of a structure area of interest (AOI). The mobile computing device receives user and/or third party data and creates UAV control data and a flight plan. The mobile computing device executes a flight plan by issuing commands to the UAV's flight and camera controller that allows for complete coverage of the structure AOI.

After data acquisition, the mobile computing device then transmits the UAV output data to a server for further processing. At the server, the UAV output data can be used for a three-dimensional reconstruction process. The server then generates a vector model from the images that precisely

(Continued)



represents the dimensions of the structure. The server can then generate a report for inspection and construction estimation.

20 Claims, 15 Drawing Sheets

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See application file for complete search history.

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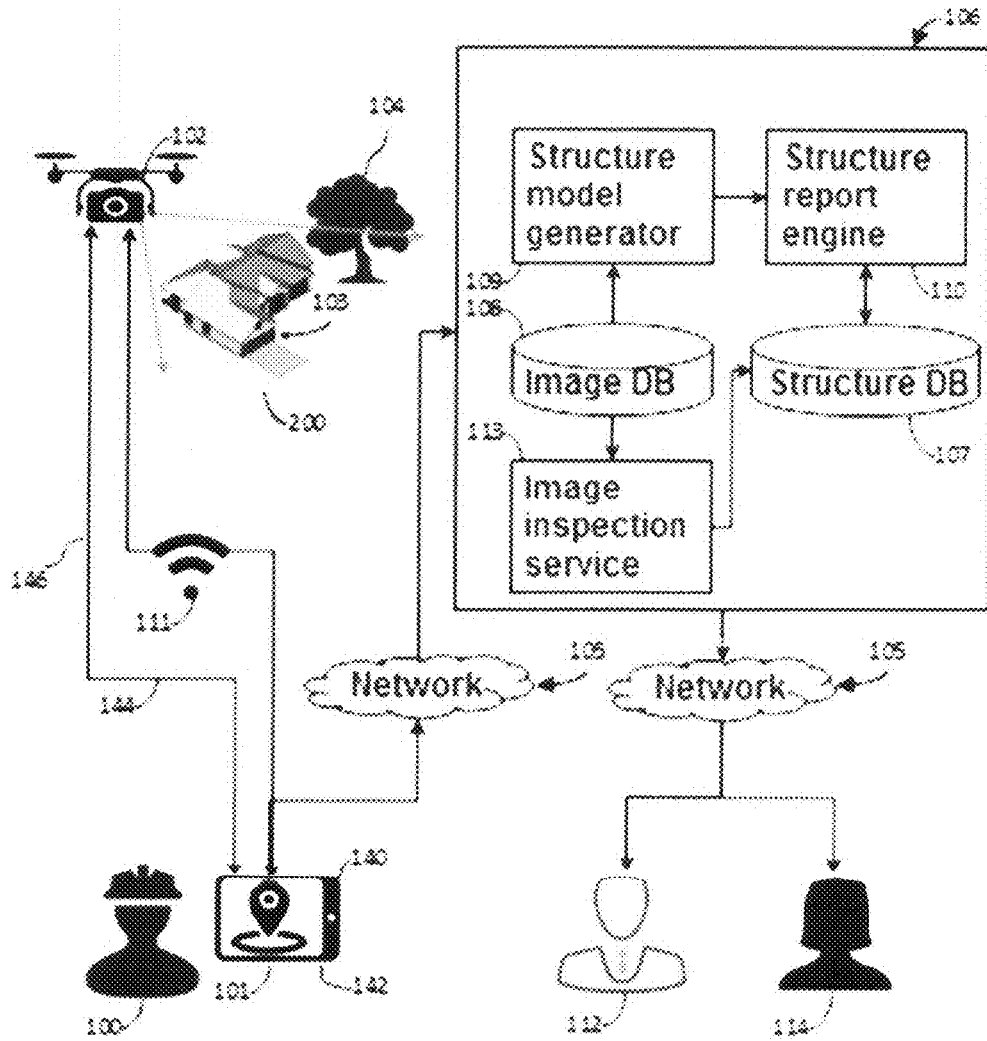


FIG. 1a

101

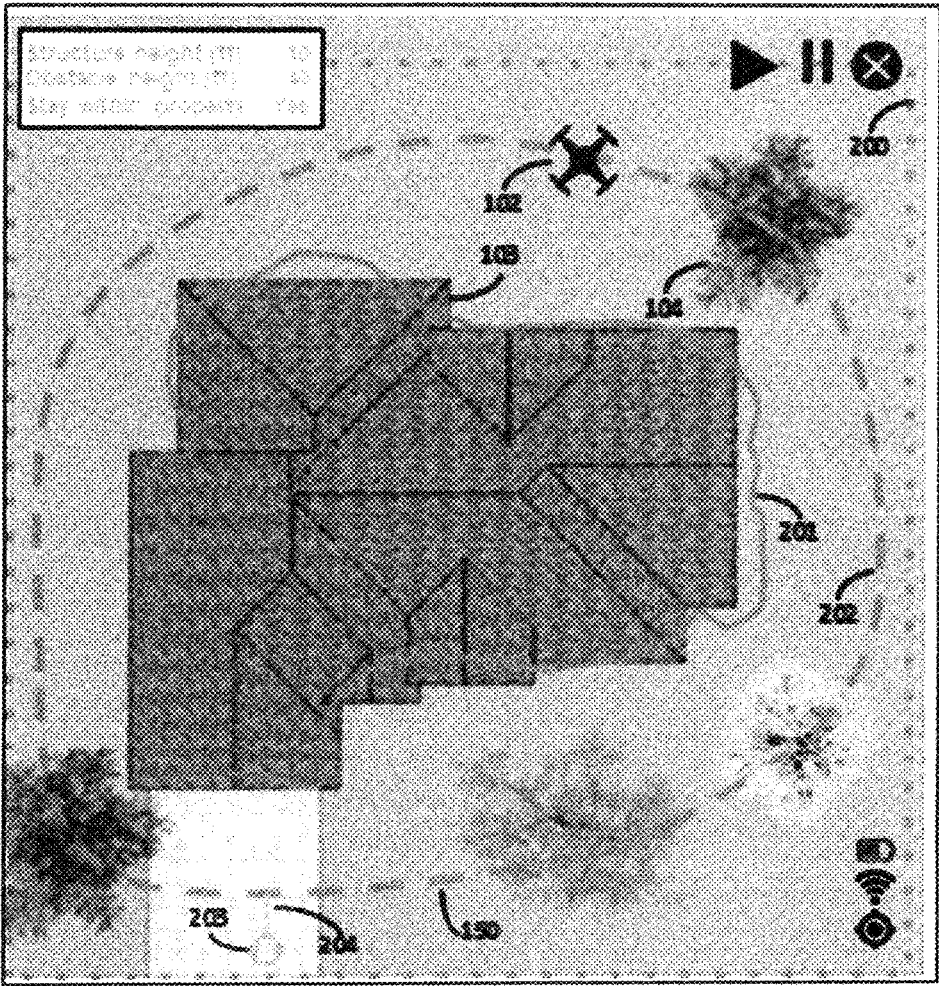
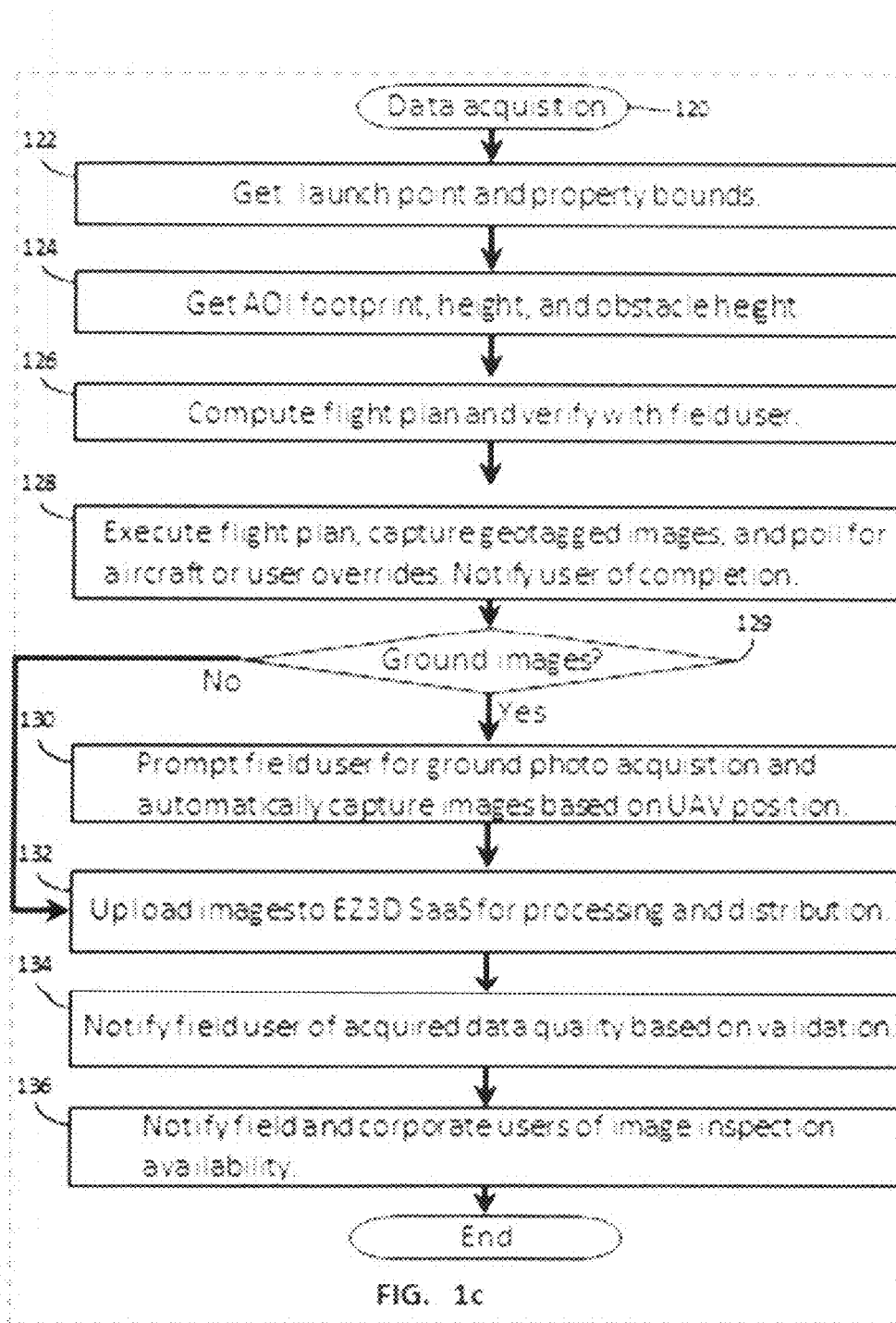


FIG. 1b



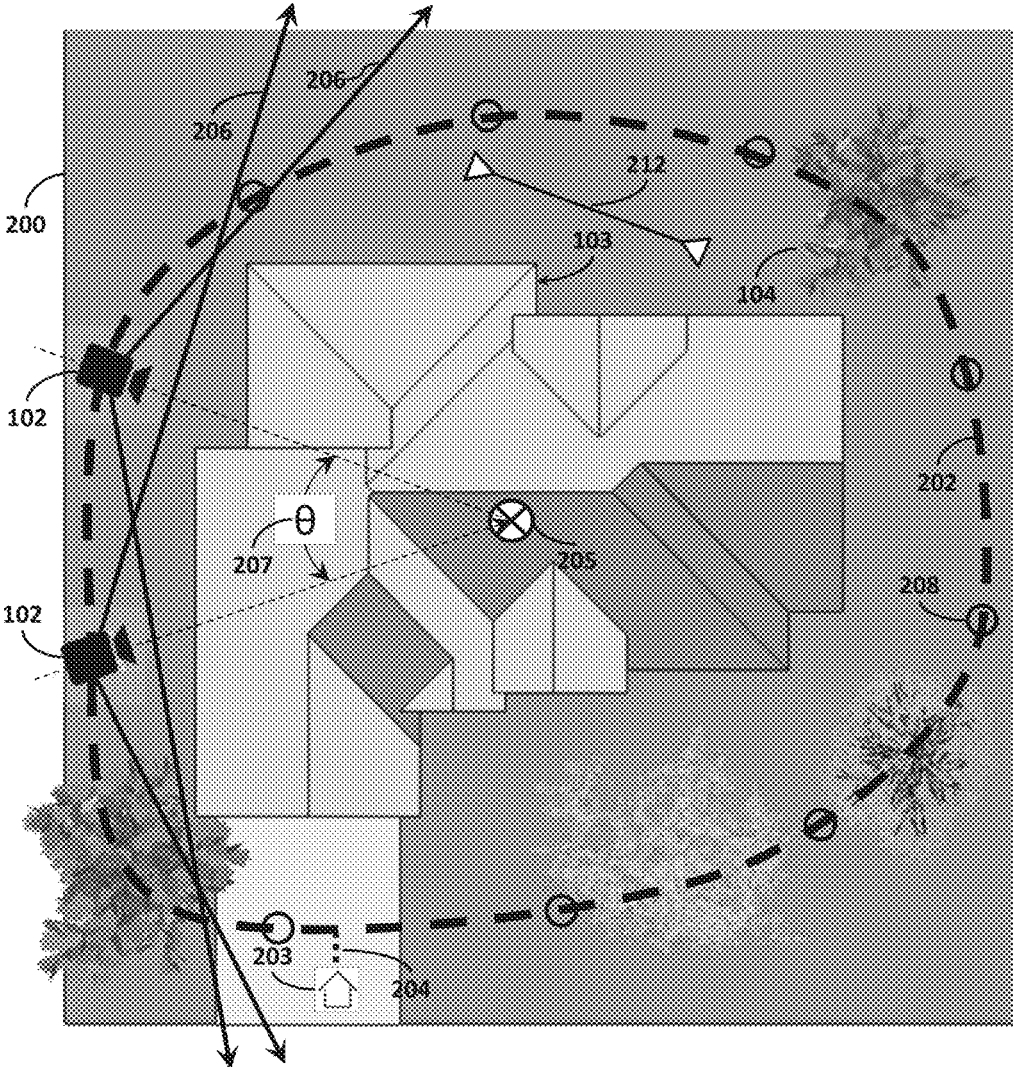


FIG. 2a

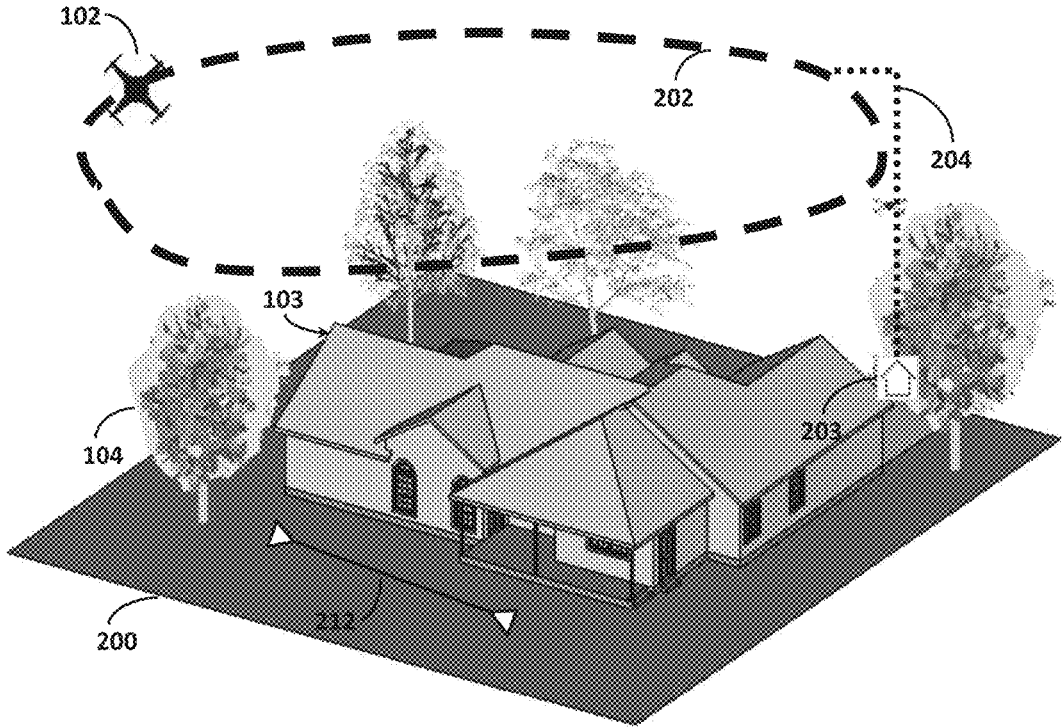


FIG. 2b

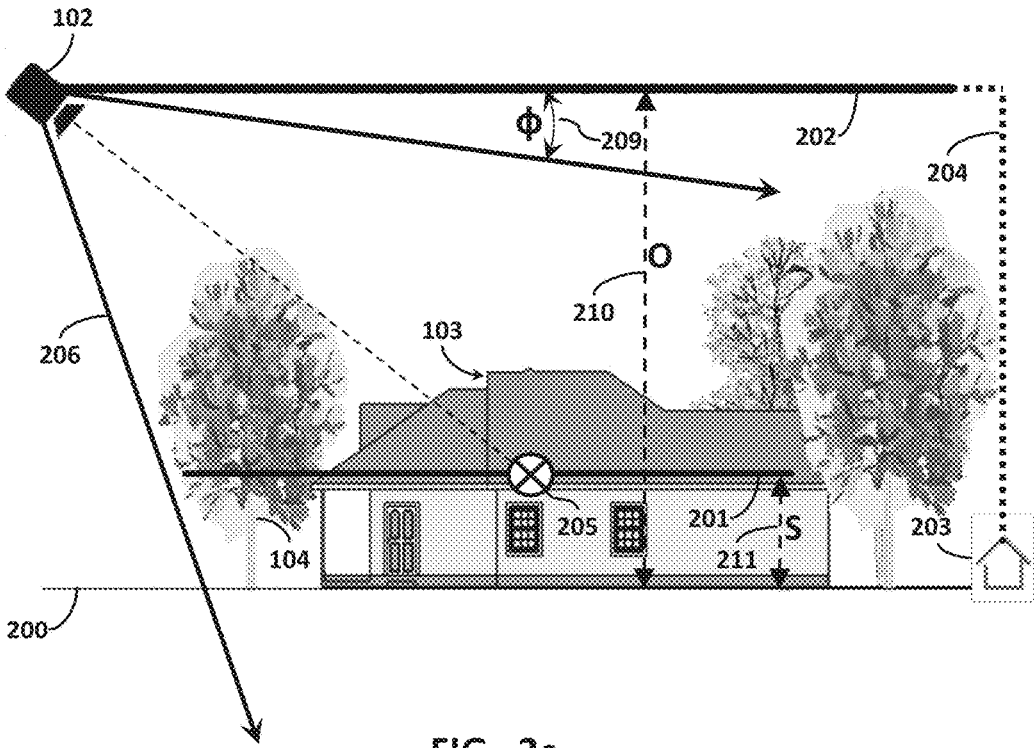


FIG. 2c

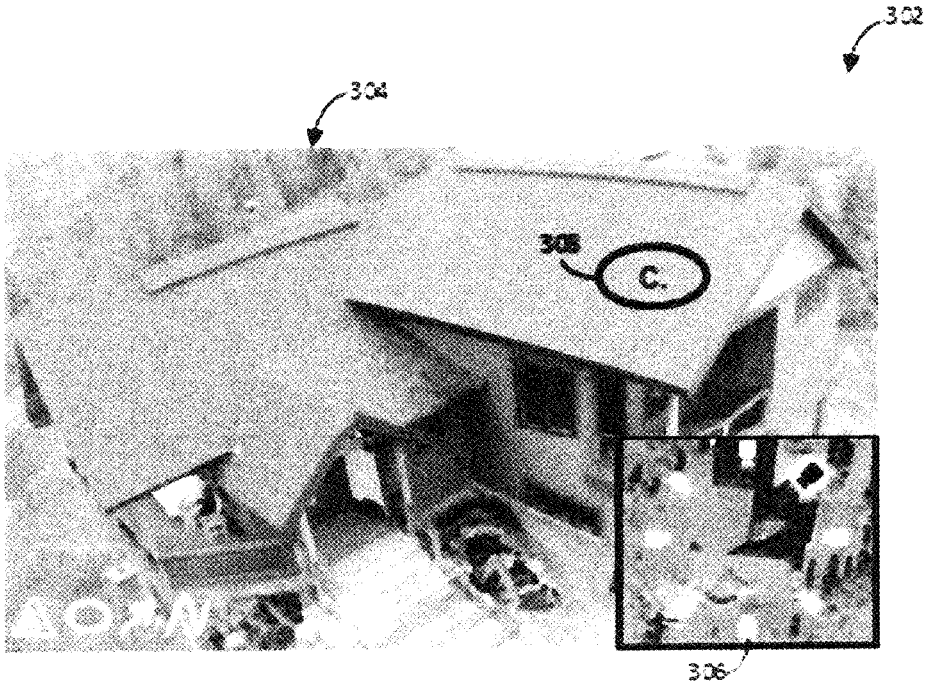


FIG. 3

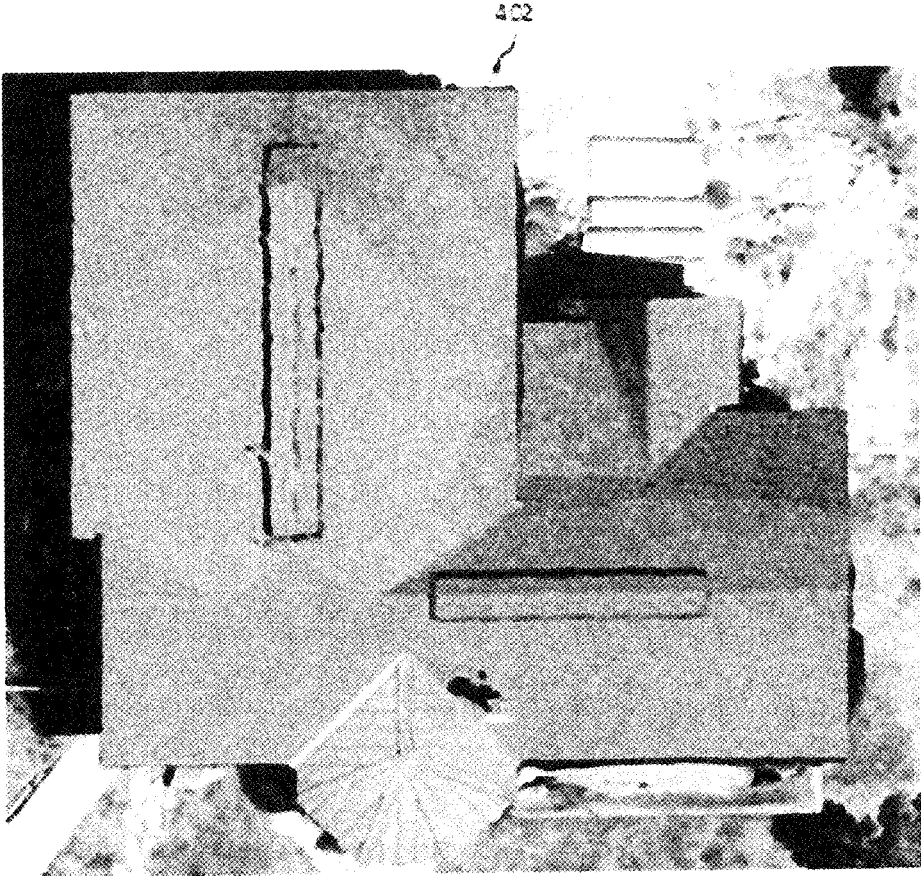


FIG. 4a

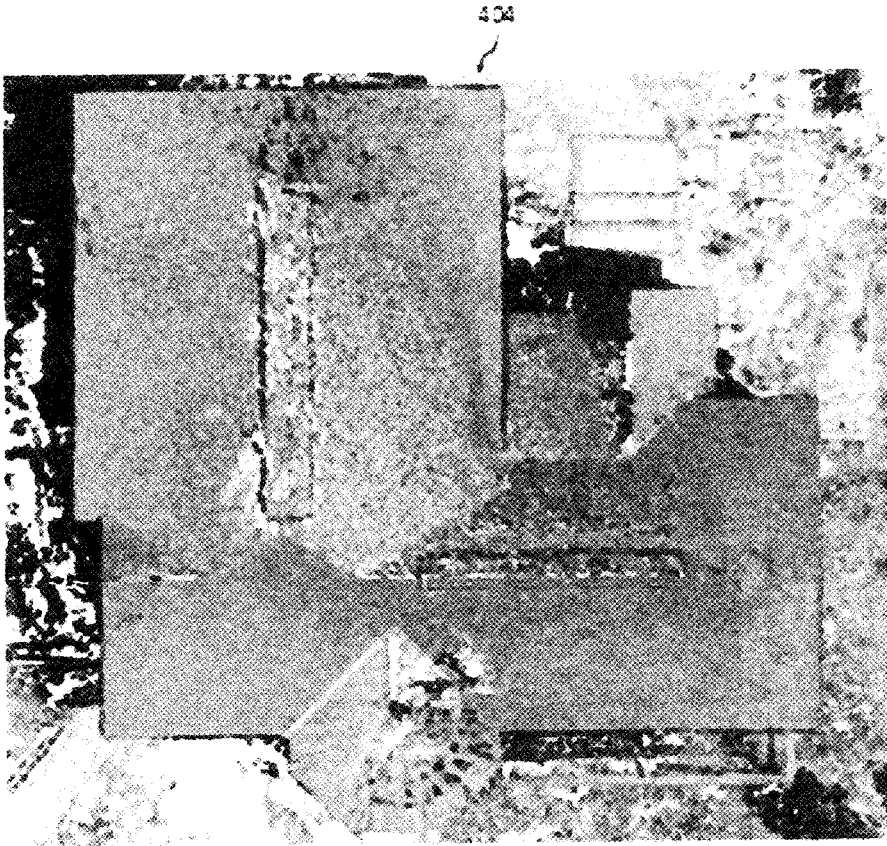


FIG. 4b

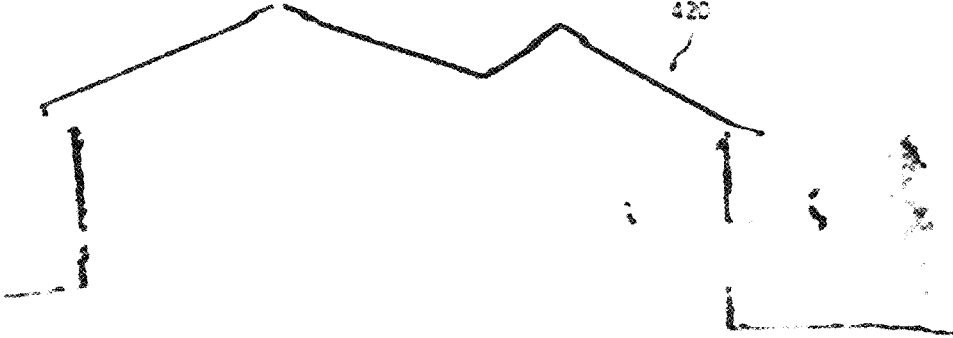


FIG. 4c

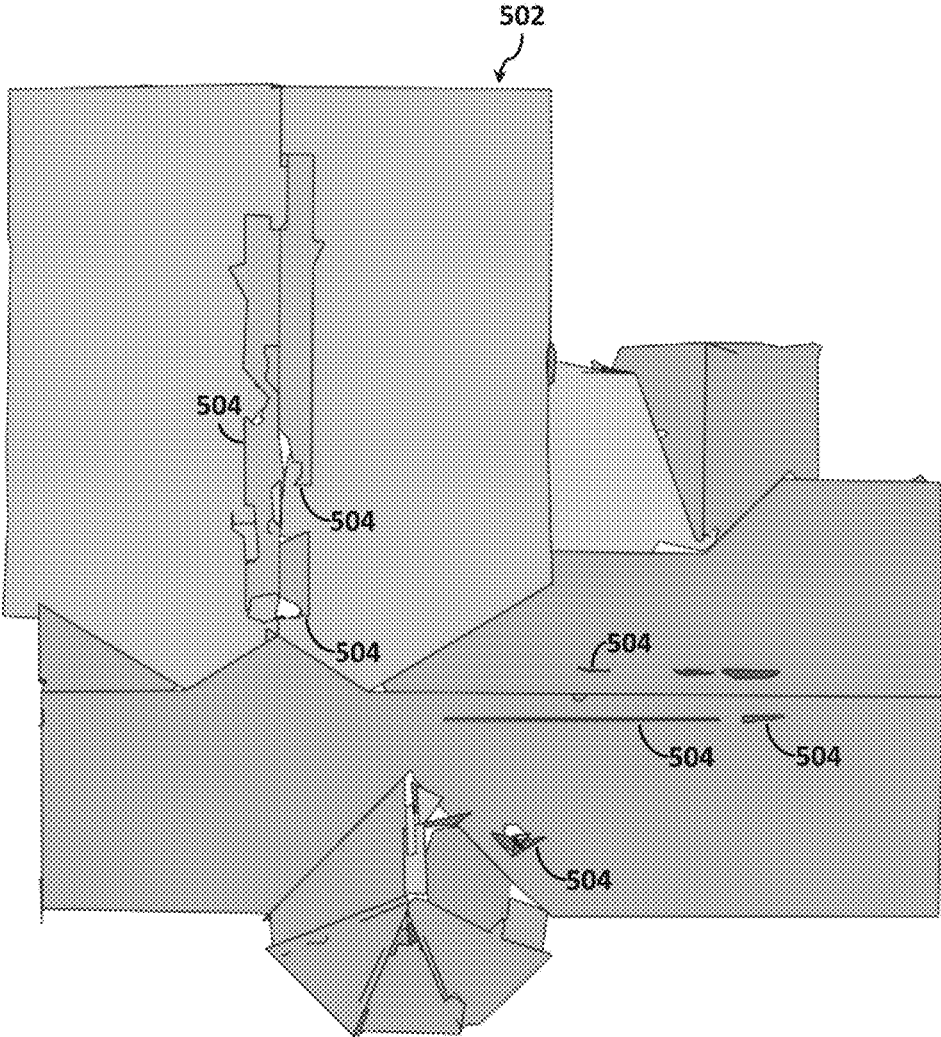


FIG. 5a

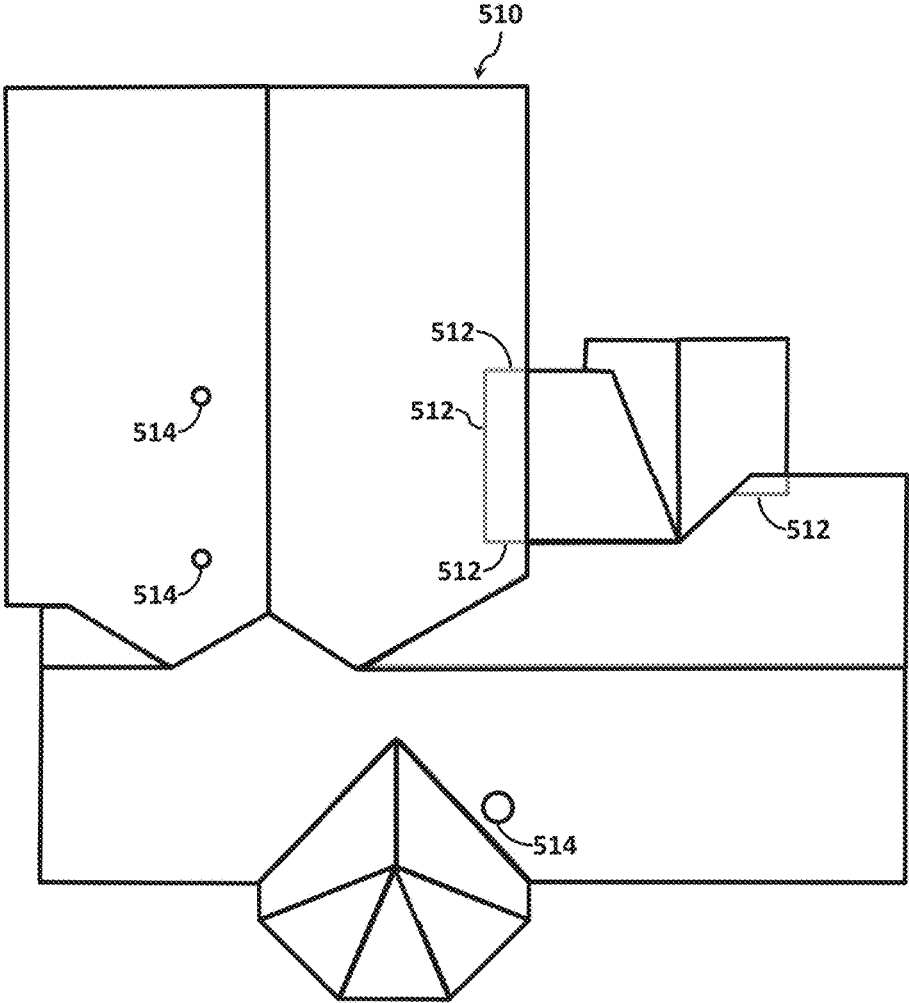


FIG. 5b

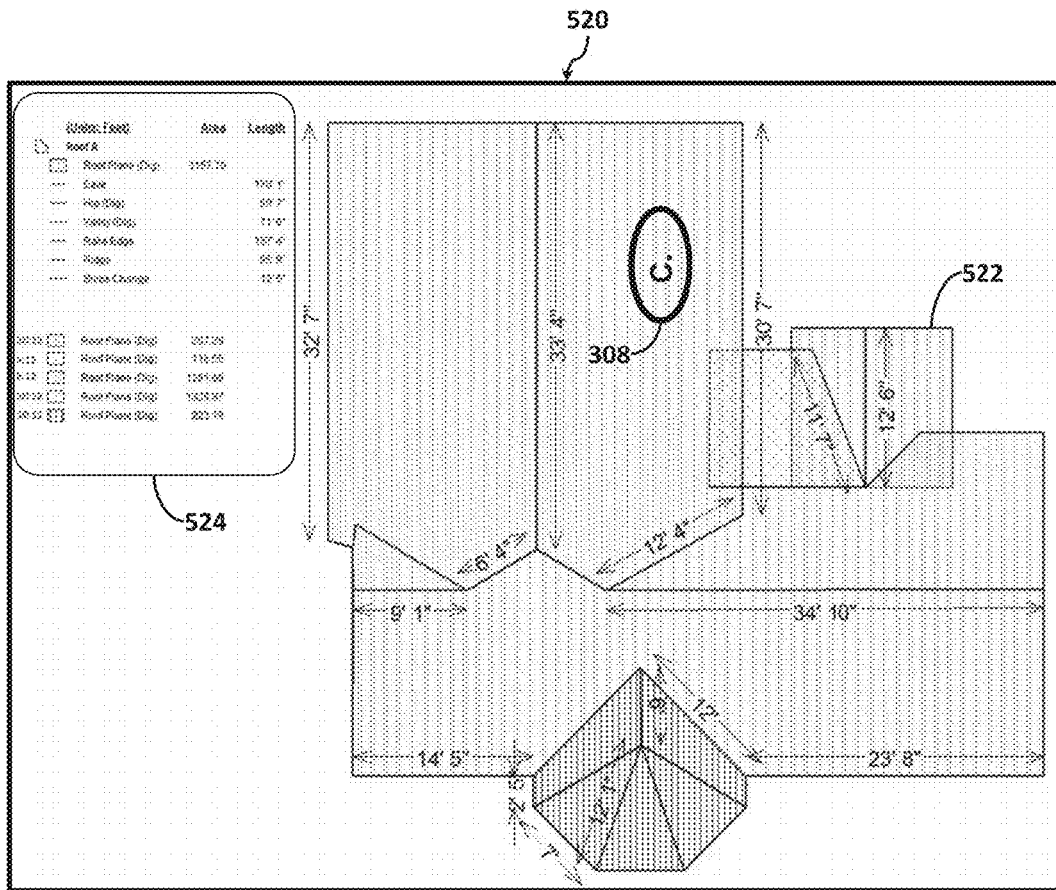


FIG. 5c

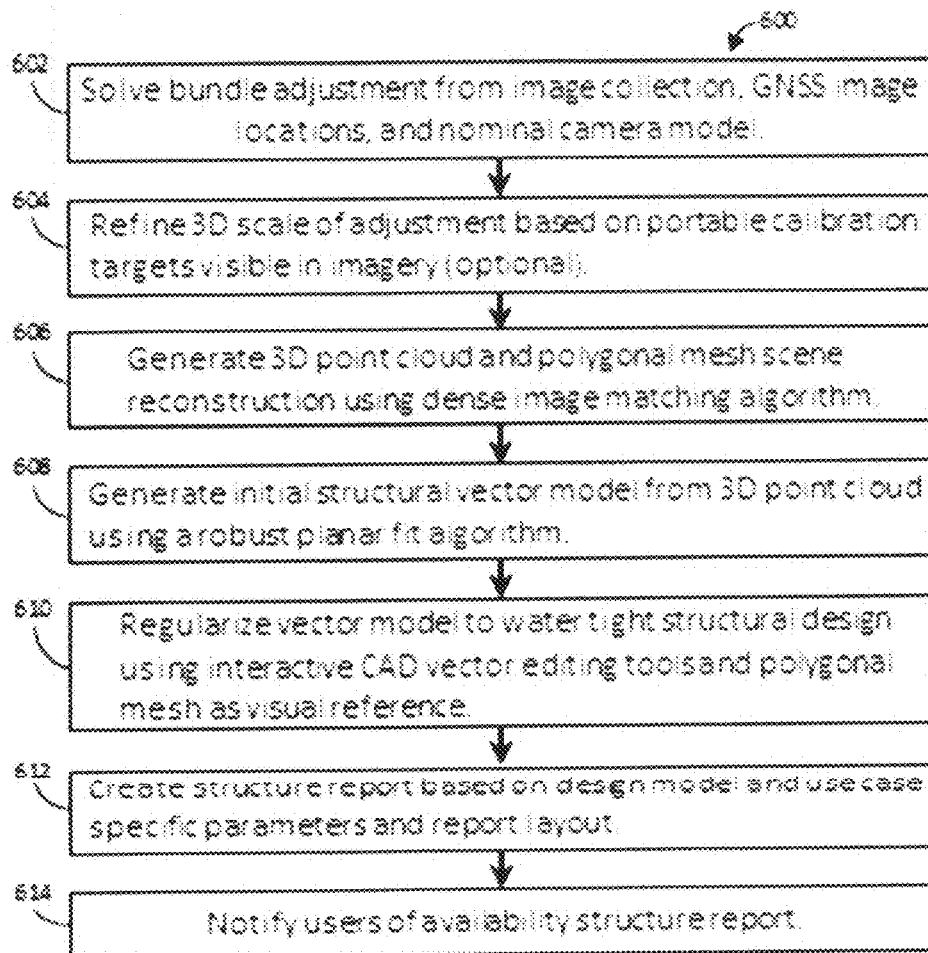


FIG. 6

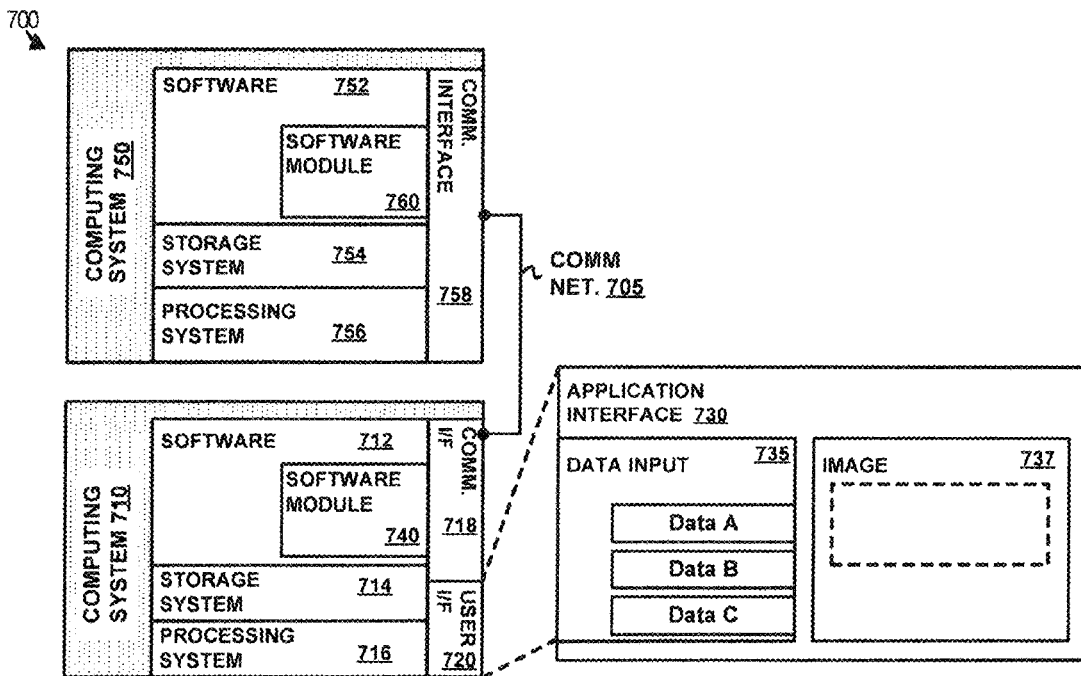


FIGURE 7

**SYSTEM AND METHOD FOR STRUCTURAL
INSPECTION AND CONSTRUCTION
ESTIMATION USING AN UNMANNED
AERIAL VEHICLE**

CROSS-REFERENCE TO RELATED
APPLICATION

This application claims the benefit of U.S. Provisional Patent Application No. 62/280,803, filed on Jan. 20, 2016, which is hereby incorporated herein by reference for all that it discloses.

TECHNICAL FIELD

The present disclosure relates to a system and method for capturing and processing images and more particularly to an automated system and method for structural inspection and construction estimation using images from an unmanned aerial vehicle (UAV).

BACKGROUND

There has been a demonstrated widespread need for a better process to obtain three-dimensional measurement and high resolution imagery for inspection and documentation of structural features that are dangerous to access directly. Very large investments continue to be made to acquire oblique image archives that capture imagery over broad areas with relatively limited resolution, redundancy, and accuracy compared to the imagery attainable through the use of UAVs. Previously disclosed methods for UAV image and data acquisition conducive to three-dimensional modeling and efficient inspection lack adequate simplicity, reliability, and affordability for common usage by untrained operators.

Ground based survey techniques by contrast are notoriously slow, prone to obstructions, and often require acquisition expertise and deployment of expensive sensors. Previous aerial Computer Aided Design (CAD) structural modeling approaches that rely on image edge detection to delineate facet seams are prone to fail with shadows, low contrast lighting, low texture building material, gutters or subtle slope changes. Structure modeling from three-dimensional point clouds fail where point density or accuracy is inadequate to cover needed surface facets with sufficient redundancy.

For a variety of purposes, the condition of building exteriors regularly needs to be assessed to evaluate and to permit cost effective maintenance and repair. Likewise, detailed structure measurement is required prior to repair or renovation. Architectural design plans, if available, are often an insufficient measurement source due to the need for reliable and current as-built dimensional data.

The construction and insurance industries expend substantial time and effort in performing both inspection and measurement of structures. Experienced field workers often physically survey the structure and document the condition, scope, and cost of repairs. This assessment and estimation work is costly, time sensitive, and often dangerous. The resulting documentation is incomplete, subjective, and prone to dispute after the work is completed.

These problems are particularly pronounced for portions of a property that are difficult to observe due to the size, height, slope, and/or location of the structure. Repairs are often urgently needed after catastrophes or severe weather. Time pressures to complete those repairs can further increase the likelihood of delays, errors, and fraud. For

example, many residential roofs will need to be inspected and measured by both roofers and insurance adjusters after a hailstorm. For steep roofs, safety concerns often require deployment of multiple field workers who typically collect and document measurements with tape measures and hand sketches. Roof condition is documented by a jumble of phone photos and surface chalk markings at precarious locations.

Installation of roof top solar arrays also require measurements of roof facets as well as protrusions such vent caps, vent pipes, vent stacks, antennae, and skylights that constrain array placement. Estimators climb up on roofs to subjectively assess where the arrays can be placed, the pitch and orientation of each facet with respect to the sun, and how much sunlight will be shadowed by nearby trees, air conditioning units, or neighboring buildings. Often a photo mosaic is captured by the technician from on top of the roof for a visual record of the roof area, but this perspective is highly obstructed compared to aerial photos. CAD modeling systems are available to precisely design solar array layout and forecast electrical yield of an array based on this information but the as-built CAD geometry including detailed protrusion locations and tree models are not readily obtainable from an efficient data collection and information extraction process.

Aerial photography. As the use of aerial-captured imagery and design models has become more prevalent in the insurance and construction industries, the associated deliverables result in the need for information that is more current, accurate, broadly available, and readily available to manage and repair structures of interest. Various features of a property critical for accurate construction or repair estimates are often not visible in aerial imagery archives because of limited coverage, inadequate resolution, occlusions from trees or roof overhangs, and out dated content. Limitations of resolution and camera perspectives also impact the detail, precision, and completeness of automatically obtainable three-dimensional measurement from these sparsely captured aerial archives which in turn leads to subjective and highly manual sketching techniques described in the prior art for design modeling.

The shortcomings of maintaining regional aerial image archives become prevalent with the increasing costs of capturing and delivering large amounts of imagery, much of which is unusable for assessing the actual condition of structures and determining the accurate repair cost parameters. As users expect higher resolution with greater detail, dated or imprecise images are not easily corrected and translated into workable models for estimation since they are typically flown years in advance of damaging events over large areas.

Ground surveys. Even with expertly captured supplemental ground level photos, it is often time prohibitive or impossible to completely capture a structure's exterior because the images needed for thorough inspection and automated measurement cannot be obtained due to vegetation occlusions, structural self-occlusions, property boundaries, terrain, or the breadth of the property.

Structured light sensors such as Microsoft Kinect and Google Tango do not work at long range or in direct sunlight. Terrestrial tripod mounted laser scanners have been used with increasing popularity among professional surveyors over the last decade and provide centimeter level precision but this approach demands hours of acquisition and processing effort by trained technicians. Furthermore, this technique typically fails to capture the entire structural exterior, especially roofs, due to obstructions, difficulty in

obtaining appropriate observation angles, hazards, and time required on site. This is especially true for structures that are built on hillsides, closely adjacent to other structures, or that are surrounded by shrubs, trees, or fencing.

Other UAV techniques. Some UAV mapping surveys may be performed from a series of downward pointing (nadir) photos captured in a linear grid pattern over an area of interest requiring a series of inefficient U-turn maneuvers and offering little or no overlap between the initial and final photos in the series. Tree tops severely disrupt image matching at low altitude and image collections that do not maintain persistent oblique focus on the structure to be measured will yield reduced accuracy because large groups of photos will not be usable to reconstruct the structure completely. Overlap between photos can become irregular if the photos are not captured precisely where and when planned from such piecewise linear trajectories. These inherent flaws yield reduced measurement accuracy—large groups of photos fail to provide a basis for the complete and consistent reconstruction of a structure. Furthermore, these techniques demand professional quality aircraft hardware to ensure precise aircraft positioning, attitude sensing, and camera stability especially in high wind or low light conditions.

Ground based GPS/GNSS correction with costly and heavy receivers may be needed to correct time varying errors. Cheap and lightweight rolling shutter cameras are not typically by the aerial survey community because of distortions introduced during photogrammetric matching from low redundancy photo collections. Even middle grade consumer camera systems are often blamed for inadequate photogrammetric reconstruction when in fact results could actually be improved with better image collection techniques.

Multi directional oblique camera rigs that are often used for three-dimensional reconstruction of structural facades are prohibitively heavy for affordable and safe micro UAVs. Nadir photos even from wide angle lens do not capture facades redundantly enough for reliable reconstruction. Oblique image coverage with UAVs has occasionally been demonstrated with ad hoc, unreliable, time-consuming manually steered acquisition procedures that are not generic or simple enough for casual field operators to use regularly.

Excessive data collection increases data transfer and management costs and reduces efficiency of remote inspection. High resolution oblique photos captured without a means to precisely mask out the unintended coverage of neighboring properties prior to distribution raises the possibility of privacy actions. More sophisticated UAV acquisition strategies demand either scarce a priori or compute intensive real-time three-dimensional models or do not ensure image collections are optimally designed for automated reconstruction and contains adequate context for easy visual inspection.

The three-dimensional reconstruction of structural surfaces captured with nadir or inadequate oblique imagery will contain conspicuous voids especially for lightly textured low contrast surfaces or surfaces that are partially obstructed by trees which makes automated three-dimensional vector modeling extremely challenging.

Aerial LIDAR. Much prior research has been devoted to modeling structures from LIDAR point clouds partly because laser measurements are quite precise from high altitude flights when captured with high cost sensor and inertial measurement systems. Automated point cloud clustering techniques have been proposed to convert sparse precise LIDAR data into structural point cloud models but

fail to capture details of a meter or less in size due to limited point density (less than twenty points per meter).

Heavy high frequency LIDAR sensors can penetrate vegetation and reduce obstructions from trees compared to photogrammetric reconstruction obtained from a sparse photo acquisition. However, LIDAR systems cost over ten times more and are five times heavier than camera-only micro UAV systems that are manufactured in the millions for the consumer drone market. Furthermore, LIDAR systems cannot get resolution of ground-angle views of structures or areas of interest.

The lightest and most affordable LIDARs lack sufficient power or collection speed to make rapid and reliable data collection possible. The added cost, weight, and energy demands makes LIDAR infeasible for on demand field measurements of specific properties. Even if LIDAR was practical to use for measurement, camera data would still need to be collected as well for manual or automated visual inspection.

SUMMARY

An automated image capturing and processing system and method according to an embodiment allows a field user to operate a UAV via a mobile computing device to capture images of a structure area of interest (AOI). The mobile computing device displays the launch or home location where the UAV was initialized and will launch from and land near as part of the flight plan. The mobile computing device receives user and third party data which includes the property bounds, the structure area of interest (AOI), the structure AOI's height, and height of any obstacle(s).

In one embodiment the mobile computing device then creates UAV control data based at least in part on the user input data and/or the third party data. The UAV control data is then used by the mobile computing device to create a flight plan based at least in part on the UAV control data that assures that images and data capturing are taken at optimal distances and intervals for three-dimensional reconstruction with required resolution. In one embodiment, the UAV control data defines a flight plan composed of a launch trajectory and an acquisition trajectory that permits multiple images to be captured of the structure from a flight plan passing well above obstacles.

The mobile computing device transmits the UAV control data to a UAV via a communication link. The mobile computing device then executes a flight plan by issuing commands to the UAV's flight and camera controller comprising an orbit at a specified pitch angle that allows for complete coverage of the structure AOI. The mobile computing device executes a flight plan that also allows for omnidirectional orbital imaging that reduces obstructions both for inspection and three-dimensional reconstruction. The mobile computing device issues commands to the UAV's flight and camera controller via the UAV system's API to traverse a series of geographic waypoints and capture photos in specific orientations, and record camera position and orientation.

After the image and data capturing process has been completed, the mobile computing device may then receive the data and images in the form of UAV output data. In one embodiment, the UAV output data is modified and compressed and prepared for transmission to a server for further processing. In another embodiment, it is merely sent to the server. In another embodiment, the UAV output data is sent directly from the UAV to the server.

At the server, the UAV output data can undergo publication to an Image Database for processing by a Structure Model Generator, and Image inspection service or module. A three-dimensional reconstruction process may initially match images and may perform bundle adjustment to refine estimates of the camera exposure positions. The server then generates a regularized vector model from the images that precisely represents the dimensions of the structure.

The three dimensional reconstruction process generates an accurate design model of the structure AOI's exterior surface. The three dimensional model is a more accurate representation of the actual structure AOI being surveyed that is reconstructed entirely from real-time UAV data such that detailed construction estimates can be generated for various structural repairs, maintenance, or enhancements. In one embodiment, the server can generate a condensed report for inspection and construction estimation, and other analysis and reports.

The subject of the present disclosure provides for: (1) quickly, safely, and reliably capturing detailed and precisely geotagged imagery of an entire structure exterior or other AOI using a UAV without requiring manual piloting skills, constant control, or costly field operator trial and error of the field operator; (2) capturing imagery on demand such that the entire structure AOI is visible from a variety of perspectives for detailed remote inspection and easy recognition in less time than it takes to walk around the area without even needing to climb a ladder; (3) acquiring imagery such that accurate and complete three-dimensional reconstruction of the structure AOI can be quickly computed and a structural design wireframe model and/or a regularized vector model, of the building can be automatically derived from a dense three-dimensional point cloud; (4) providing a structural report enumerating surface type, area, condition, slope, and dimensions that can be quickly compiled from the three-dimensional wireframe or regularized vector model, photo textured polygonal mesh, and image inspection results, which is suitable for accurate repair or enhancement cost estimation; and (5) using small, lightweight, inexpensive UAVs that can be flown safely over people and locations according to FAA regulations.

BRIEF DESCRIPTION OF THE DRAWINGS

FIG. 1a is a schematic diagram of an embodiment showing the system being used to control a UAV to capture imagery of a structure.

FIG. 1b is a schematic depiction of a user interface of a mobile computing application used by a field user, according to an example.

FIG. 1c depicts a method of workflow for an embodiment.

FIG. 2a is an overhead orthographic diagram, according to an embodiment.

FIG. 2b is an axonometric diagram, according to an embodiment.

FIG. 2c is a side orthographic diagram, according to an embodiment.

FIG. 3 is an example user interface and application snapshot illustrating one of several very high resolution oblique UAV photos selectable from a map image inset being used for structural inspection.

FIG. 4a illustrates an example of a three-dimensional polygonal photo textured mesh of a building viewed from overhead that was automatically generated from a collection of oblique UAV acquired images such as the one shown in FIG. 3.

FIG. 4b illustrates an example of a three-dimensional dense point cloud of a building viewed from overhead that was generated from oblique UAV acquired images such as the one shown in FIG. 3.

FIG. 4c shows an example of a three-dimensional dense point cloud of the building shown in FIG. 4b, viewed from oblique and ground level cross section perspectives.

FIG. 5a illustrates an example of a three-dimensional polygonal facets of an intermediate building model viewed from overhead as shaded surfaces that were generated from the three-dimensional dense point cloud shown in FIG. 5b.

FIG. 5b illustrates an example of a three-dimensional building model viewed from overhead as a wireframe generated from the three-dimensional polygonal facets (from FIG. 6a) and photo textured mesh (from FIG. 5a).

FIG. 5c depicts an excerpt from an exemplary "aerial CAD" structural report used for roof repair use cases.

FIG. 6 depicts an example method for generating a structural model from UAV imagery and is used to generate a report suitable for estimating cost of construction.

FIG. 7 is a computing environment, according to an embodiment.

DETAILED DESCRIPTION

Description of FIGS. 1 and 2—Architecture and Data Acquisition. The overview diagram shown in FIG. 1a depicts an embodiment of a data capture system and method where a field user 100 such as an insurance adjuster or roofing company estimator with a mobile computing device 101, such as a tablet, computer, smartphone, or any other device capable of functioning as described herein.

Device 101 may have an application that maintains connectivity via a local wireless network protocol 111 or other connection to a UAV or drone 102 in order to acquire geotagged images of the structure 103 while flying above common obstacles or obstructions 104, such as utility wires or trees, but within a given property boundary 200 of the building owner or manager 114.

The mobile computing device 101 may be capable of running an operating system, such as the Android or Apple operating system, that can sufficiently control a UAV 102 such as a DJI Phantom, three-dimensional Robotics Solo, Yuneec Typhoon, or Microdrone MD4 series or other UAV 102 via Wi-Fi or other connection, such that GPS geotagged imagery can be captured at desired geospatial locations and orientations. Efficiency provided by the system may be critical to minimize field labor and/or to preserve battery charge of the UAV 102, which may only allow for about fifteen to thirty minutes of safe flight time per charge.

FIG. 1a also shows how components of the data processing system and method interface to generate a report 520. At the end of or during the flight, images and data comprising UAV output data 146 can be transferred from the UAV's on board storage via Wi-Fi 111, SD card, or other method, to the mobile computing device 101 so that the application running on device 101 can compress, manipulate and securely upload images and data via a wide area network 105 or other connection to computer servers 106 running web services. In some embodiments, the UAV output data 146 can be transferred from the UAV 102 directly to a server 160, via, for example, long-term evolution (LTE) or other wired or wireless communication.

The images and their geotags may be stored in an Image Database 108 and are generally immediately made available to enterprise and other users 112 via an Image Inspection Service 113. Generally in parallel, a three-dimensional

reconstruction processing of the image data set may be performed by a Structure Model Generator **109**, which performs initial quality checks on the data to verify the acquired data is usable and can issue a notification to the field user **100** if data needs to be reacquired.

Once three-dimensional reconstruction and image inspection is completed, use case specific report generation is performed by a Structure Report Engine **110** where reports **520** are published into a Structure data base **107** for review by the enterprise or other user **112** and property owners **114**.

An example user interface of a mobile computing device **101** in FIG. **1b** illustrates example data capture and pre-processing. An example acquisition process begins with the field user **100** initializing a network connection between the mobile computing device **101** and UAV **102** via the wireless network **111** illustrated in more detail FIG. **1a**.

The mobile computing device **101** displays the launch or home location **203** where the UAV **102** was initialized and will launch from, and land near, as part of the flight plan **150**. The mobile computing device **101** receives user input data **140** at least in part via the user interface of device **101**, from the field user **100** which includes the property bounds **200**, the structure area of interest (AOI) **201**, the structure AOI's height **211**, and the obstacle clearance height **210**, if any.

The mobile computing device **102** allows the field user **100** to designate a polygon approximating the property bounds **200**. This polygon **200** can be designated by (a) sketching with the mobile computing device **102** interface over the apparent property lines **200** in the application's map image display, (b) tracking the mobile computing device's GNSS (global navigation satellite system) or GPS (global positioning system) position as the field user **100** walks around the property perimeter **200**, or (c) retrieving third party data **142**.

The third party data **142** could include the geographic boundary from a public or commercially available database, based on the property mailing address or geolocation, location information from the UAV **102**, or information from other sources, for example, Google Maps, and may be based on GPS location, among others.

Similarly, the structure area of interest (AOI) **201** can also be designated by either quickly sketching over the map image or tracking a GPS transect paced off by the field user **100** carrying the mobile computing device **101**. The structure AOI **201** needs to crudely approximate the actual structure boundary **103** in order to avoid clipping the structure **103** from image bounds during data capture.

The structure AOI **201** height **211** and obstacle clearance height **210** may need to be numerically specified for the flight plan **150**. In one embodiment the mobile computing device **101** then creates UAV control data **144** based at least in part on the user input data **140**, the third party data **142**, or data that is empirically derived from the UAV **102** itself, which could include GPS data or a nadir image or photo mosaic of a the property AOI **201** from a specified elevation. The UAV control data **144** is then used to create a flight plan **150** based at least in part on the UAV control data **144**, which may include the property bounds **200**, if specified, the structure AOI **201**, the structure AOI's height **211**, and the obstacle clearance height **210**, if any, and other information.

This assures that images and data capturing are taken at optimal distances and intervals for three-dimensional reconstruction. In one embodiment, the UAV control data **144** defines a flight plan **150** composed of a launch trajectory **204** and an acquisition trajectory **202** that permits multiple images to be captured of the structure **103** or structure AOI **201** from a flight plan **150** well above obstacles **104**.

The mobile computing device **101** may then transmit the UAV control data **144** to a UAV **102** via a communication link **111**. The mobile computing device **101** allows the field user **100** to start, pause, resume, or abort the flight plan **150** and track the UAV **102** position as well as display imagery from the camera in real-time. While the acquisition trajectory **202** is paused or after it has been completed, the field user **100** can manually control the UAV **102** with or without the aid of onboard obstacle avoidance systems to for instance, capture supplemental images of interest such as close up photos of defective features before resuming the flight plan **150**.

The mobile computing device **101** then executes a flight plan **150** by issuing commands to the UAV's flight and camera controller. The commands can include an orbit at a specified depression angle Φ , **209**, or pitch angle, that allows for complete coverage of the structure AOI **201**. The mobile computing device **101** executes a flight plan **150** that also allows for omnidirectional orbital imaging that reduces obstructions both for inspection and three-dimensional reconstruction.

In other embodiments, images can be captured in multiple acquisition trajectories **202** with various fixed elevations if the structure AOI's **201** façade is highly obstructed and the use case demands a more complete reconstruction of exterior walls. Images can also be captured in multiple acquisition trajectories **202** with varying ranges to support a variety of use cases that demand higher resolution imagery. A pyramid of higher resolution imagery covering all or parts of the structure **103** can be collected for inspection purposes so that even very detailed images covering very small portions of the structure **103** can be automatically matched allowing rapid indexing of the image collection and preventing fraudulent exchange of imagery from another property. In some embodiments, an acquisition trajectory **202** can have varying elevations and be computed dynamically if an automated obstacle detection system is available on the UAV **102** or the operator manually controls the UAV elevation.

FIG. **1c** provides an example method workflow diagram for data acquisition **120**. The process begins at **122** by gathering user input data **140** and/or third party data **142** from the UAV's onboard flight control system for the home point **203**. The property boundary polygon **200** may be received from the mobile computing device **101** via user input data **140** or from third party data **142**.

Next at **124**, information about the structure AOI **201**, the structure's approximate height **211**, and obstacle clearance height **210**, such as trees, utility wires present near the structure are reviewed. With the user and/or third party inputs, the mobile computing device **101** formulates the UAV control data **144** that can compute the flight plan **150** and present it to the field user **100** for verification **126**.

In an embodiment, upon user approval, the mobile computing device **101** executes the flight plan **150** using the UAV control data **144** by issuing commands to the UAV's flight and camera controller via the UAV system's API to traverse a series of geographic waypoints, and capture photos in specific orientations, and record camera position and orientation. While executing the flight plan **150**, the mobile computing device **101** also has to poll for interrupts from the field user **100** to pause, resume or abort the flight plan **150**. It also has to poll for interrupts from the UAV flight controller and alert the field user **100** as to flight status, such as UAV position, UAV battery charge remaining, and GNSS status. The mobile computing device **101** also allows the field user **100** to alter the flight plan **150** to, for example,

alter the altitude of the flight plan **150** in order to maintain a safe height above obstacles **210** in case the obstacle elevation data was initially incorrect.

Based on whether the field user **100** requires ground level images **129**, the mobile computing device **101** will enter a mode with the propeller motors disengaged to capture images while the field user **100** is holding the UAV **102** with the camera pointed towards the structure AOI **201** and traversing the flight path **130** generally. The images captured and other data constitute UAV output data **146**, which is transferred from the UAV **102** to the mobile computing device **101**.

In an embodiment, mobile computing device **101** may then compress or otherwise modify the images and data and transmit **132** the UAV output data **146** to a server, where the UAV output data **146** can undergo publication to the Image Database **108** for processing by the Structure Model Generator **109** and Image Inspection Service **113**. The UAV output data **146** may also contain metadata comprising, for example, the UAV acquisition trajectory **202**, and the time, latitude, longitude, elevation, heading, pitch, roll, deltax, deltax, deltax, and GNSS Dilution of Precision at each exposure time.

The three-dimensional reconstruction process initially matches images and performs bundle adjustment to refine estimates of the camera exposure positions. If this is unsuccessful the problem can be characterized within minutes of upload and the field user **100** can be notified through the mobile computing device **101** that a problem occurred during acquisition **134**. If the image collection passes acquisition validation, the mobile computing device **101** may provide an indication. Enterprise users **112** and other users can be notified of availability through image inspection services **136**.

FIGS. **2a**, **2b**, and **2c** illustrate example design parameters of the data acquisition system and method that allow the system to efficiently and reliably capture data suitable for structural inspection and complete, accurate three-dimensional reconstruction with consumer grade UAV hardware by field users **100** with minimal operational training. This method allows for fully automated operation from takeoff to landing without need for any manual flight or camera controls except to override, interrupt, or abort the plan as needed.

The structure AOI **201** and optional property boundary **200** shown in FIG. **1b** serve as the planimetric basis of the flight plan's **150** acquisition trajectory **202**. The images are captured at camera exposure stations **208** along the trajectory **202** such that successive camera positions are angularly separated by less than an angle θ **207** with respect to the AOI centroid **205**. Theta **207** is the maximum separation angle between camera positions **102** that permits reliable correlation matching during image reconstruction. In one embodiment, θ **207** is roughly 10 degrees.

The orientation of the camera at each station should be generally orthogonal to the trajectory **202** so that the UAV's camera gimbal does not need to fully yaw steer. This allows for simple gimbal hardware such as those used on the DJI Phantom 1, 2, 3 and 4 series and other popular consumer grade UAVs **102**.

In an embodiment, there may be two geometric transformation algorithms that are applied to the structure AOI **201** to ensure that the camera exposure stations **208** are conducive to three-dimensional reconstruction with a UAV **102**. First, a convex hull is computed that eliminates concavities in the trajectory **202** that would lead to diverging perspectives and reduced overlap between successive exposures.

Next, a dilation operation is applied with a circular structuring element with radius selected to maintain angular separation θ **207** with a minimum number of total images.

The trajectory **202** can then be constrained or clipped so that the UAV **102** does not exceed the property boundary polygon **200**, if one has been specified. At this point, the acquisition trajectory **202** has been defined horizontally as shown in FIG. **2a**, but a fixed elevation needs to be determined which ensures the entire structure AOI **201** will be contained within the bounds of each image frame and that the UAV **102** will maintain a minimum height above obstacles **210** as shown in FIG. **2c**. In some embodiments, a higher elevation than the obstacle clearance height **210** may be needed to maintain sufficient range to image the entire structure AOI **201** while staying with the property boundary **200**.

The structure bounds are defined by the structure AOI **201** horizontally and a nominal structure height **211**. The UAV camera's nominal field of view **206** can be computed from the a priori focal length used in the photogrammetric solution but should be reduced by a margin that accounts for the UAV **102** and gimbal steering uncertainty during dynamic flight under windy conditions, in one example roughly ten degrees horizontally and vertically.

Furthermore, in some embodiments, the UAV's elevation must allow for camera pitch such that a minimum depression angle ϕ **209** is positive so that very distant features above the horizon do not lead to undesirable sky or cloud points in the point cloud produced during dense matching and to reduce glare from the sun. In these embodiments, using positive minimum depression angles ϕ **209** also allows for more accurate camera auto calibration. However, in other embodiments, negative minimum depression angles ϕ **209** may be used during the acquisition phase to, for example, capture neighboring terrain for real estate promotion. In some embodiments, the depression angle ϕ **209** can be set for nadir orientation when, for example, only the structure's **103** roof needs to be reconstructed or efficient broad area inspection of multiple properties is desired.

Finally, once the three dimensional acquisition trajectory **202** has been computed, the launch or approach trajectory segment **204** must be calculated such that the UAV **102** is steered from the home point **203** vertically up to the acquisition trajectory **202** elevation and then horizontally to the nearest point in the acquisition trajectory **202**. This same trajectory **204** is reversed for landing after completion of the acquisition trajectory **202**. This vertical launch and landing trajectory **204** method ensures the UAV **102** reaches a safe flight altitude without running into obstacles **104** such as trees and without requiring advanced obstacle detection systems most commonly found on much more costly commercial UAVs **102**.

The systems and methods of the present disclosure efficiently provide for highly redundant imagery covering the vast majority of typical commercial and residential structure exteriors with dozens of images. This redundancy is very effective for (1) providing a closed loop of overlapping imagery that allows photogrammetric bundle adjustment algorithms to iteratively cancel out a variety of time varying systematic errors typical of UAV **102** systems such as GNSS position error, camera shutter timing errors, lens calibration errors, and rolling shutter distortions; (2) allowing dense matching algorithms to correlate image pairs with a sufficiently low angular separation that permits surfaces to be reconstructed with minimal point cloud voids even with limited surface texture found in many modern structural facades; (3) allowing both three-dimensional reconstruction

as well as image inspection to be complete despite trees occluding portions of the structure in some images; (4) allowing the entire breadth of the structure to be visible in each image permitting immediate intuitive recognition of the image context and thereby providing more aesthetic and useful images for sales and real estate applications than nadir images or clipped oblique close up views.

The systems and methods of the present disclosure efficiently provides for highly redundant imagery with full generality of structural shape, height, obstructions, and operator errors and requires no a priori topographic or aerial image data. In practice this technique will generate a reconstruction, or regularized vector model, that is accurately scaled in all three dimensions with less than one percent systematic relative error which means, for example, that a given ten meter edge length can be modeled to within ten centimeter error despite camera position errors of individual images exceeding three meters or more.

However, some embodiments may require better photogrammetric accuracy. In these embodiments, a simple calibration target **212** can be deployed within the field of view of multiple images. In such cases, the field user **100** can position the target **212** consisting of two brightly colored objects with readily photo identifiable central points a known, fixed distance apart. In practice, painted floor tiles joined by a low stretch fastener such as Kevlar cord pulled taut is effective and easily deployed.

The center points of these targets **212** can then be identified in two or more image pairs either manually by an operator or automatically through computer vision template matching or machine learning techniques, and can be used to correct the scale of the photogrammetric solution in all three dimensions during the structure model generation phase of processing. This technique has proven to reduce model error to roughly twice the image pixel resolution or typically two centimeters over a ten meter span, an approximate five times error reduction, with negligible added expense or effort.

The same calibration method can be used in other embodiments where a GPS signal is unavailable, degraded, or where a GPS device is not embedded in the UAV **102**, for instance where the UAV **102** is navigating using Simultaneous Localization and Mapping (SLAM) techniques.

FIG. **3** depicts an example image on the user interface of a mobile computing device inspection application **302** that is intended for use by field users **100** for inspecting the structure AOI **201** in varying respects such as automated damage detection, assessing condition and composition of the structure **103**, identifying structural features requiring maintenance, repair or replacement, assessing hazards of the site from an occupant or construction perspective, planning staging and work areas. Additionally, the imagery and associated observations recorded with the mobile computing device inspection application **302** can be used for documenting the state of the site prior to or after work has been completed.

The mobile computing device inspection application **302** as shown and described in an embodiment, may include several components, a UAV image captured from an oblique perspective **304**, a map inset **306**, displaying the structure AOI **201** with an overhead image map from an online map platform such as Google Maps or another source such as a UAV **102** captured nadir photo or photomosaic collected at a high altitude. The map inset **306** may also include camera perspective icons that provide the field user **100** an intuitive navigational interface for selecting images from the UAV image database **108** from varying perspectives.

The application **302** provides the field user **100** a means of adding annotations **308** to the image that can be categorized and added to the structure database **107** via image inspection service **113** as shown previously in FIG. **1a**. The annotation can be recorded according to its precise image coordinates or projected to an approximate geographic position based on image orientation parameters stored in the Image Database **108**, the image coordinates of the annotation, and the geographic elevation plane specified by the sum of the home point **203** elevation and the structure height **211**.

The difference in image quality between the structure shown in the UAV image **304** (at reduced resolution) and the same location shown in the Google Map inset **306** (at full resolution) provides a stark example of the increased value of data provided with the present systems and methods compared to aerial photos commonly captured currently by manned aircraft.

In some embodiments, this same geographic positioning technique can be used in reverse in order to project a subset of the polygonal mesh **402** that falls outside the property boundary line **200** into image coordinates of the inspection image(s) **304** thus creating image masks corresponding to pixels within the inspection images **304** that fall outside the property owner's **114** possession or legal right to view. This process permits the system to reduce the effective image resolution of the inspection images **304** by blurring convolution in areas outside of the property **200** being surveyed and in doing so maintain compliance with privacy regulations of some governments as well as to minimize the potential risk of privacy related law suits.

Description FIGS. **4** and **5**—Structure Model and Report. FIG. **4a** shows a three-dimensional polygonal photo textured mesh model of a building viewed orthographically from overhead **402**, according to an embodiment. It is essentially an orthographic image, or true orthomosaic, rendered from a three dimensional model that was reconstructed from the UAV output data **146**, more specifically comprising a collection of oblique UAV images such as the example image **304**.

FIG. **4a** **402** provides a convenient image underlay when editing or validating three-dimensional vector models in a variety of Computer Aided Design (CAD) products such as AutoCAD or SketchUp without needing to contend with camera model parameters and coordinate systems which greatly complicate vector to image registration in such CAD packages. FIG. **4a** also offers a more precise visual reference than conventional overhead photos because it is an exact orthographic projection containing image features that are not shifted by parallax based on their elevation.

FIG. **4b** shows a three-dimensional dense point cloud **404** colored by photos used for dense stereo matching during photogrammetric reconstruction of the UAV oblique images, according to an embodiment. It is similar to the mesh rendering **402** but contains white voids where the three-dimensional reconstruction was incomplete due to obstructions or low correlation during stereo image matching. The mesh **402** photo texture has been projected onto facets that were derived from the point cloud **404**.

The point cloud **404** is therefore a more accurate geometric reference of the structure as can be seen when viewed from other perspectives a shown in FIG. **4c**. Here the same point cloud **404** viewed from oblique perspective **410** reveals nearly complete reconstruction of roof and wall surfaces. The point cloud's **404** vertical precision is most evident from a cross section view **420** where geometric noise is minimized compared to photogrammetric results in prior art.

Both point cloud **404** and mesh **402** representations contain thousands or even millions of elements covering many small features of the structure AOI **201** and do not directly provide overall dimensions of the primary structural facets needed for a cost estimate. The system and methods disclosed herein are capable of providing yield point cloud density over the entire structure surface which is substantially uniform ranging from 100-10,000 points per square meter even for low contrast metal surfaces. This is ten times to a hundred times greater density than conventional aerial LIDAR surveys while retaining at least two centimeters vertical precision, for example, in some embodiments one millimeter to two centimeters vertical precision. Such density and precision in the point cloud **404** greatly simplifies and improves reliability of later automated steps in the building modeling process.

FIG. **5a** shows polygonal facets of an intermediate building model **502** viewed from the same orthographic overhead perspectives as shown previously in FIGS. **4a** and **4b**. This example representation begins to approximate overall facet dimensions. However, there are extraneous facets or artifacts **504** of this model that in some embodiments may be undesirable for a succinct design model.

FIG. **5b** depicts a watertight regularized wire frame vector building model **510** from an overhead orthographic perspective, according to an example. This regularized vector model **510** lacks the extraneous facets **504** apparent in the previous figure (FIG. **5a**) as well as the gaps, small jagged edge segments, and irregular edge angles. This cohesive facet relationship is commonly referred to as watertight because the edges abut perfectly without gaps. This clean appearance is standard for professional CAD models and presents the structure without distracting artifacts. Watertight geometry of the present systems and methods also allows for the classification and measurement of seam lengths which are crucial to roof repair estimation.

In embodiments where three-dimensional printing is desired, watertight geometry is needed in order for the printed object to be structurally sound during and after fabrication. The hidden edges **512** illustrate that this is a general and complete three-dimensional model with some edges that lie beneath some facets rather than a so called two-point-five-dimensional model where only one facet surface can occur over a given ground coordinate.

Additional manually added features **514** are also present in this model **510** that were not evident or completely portrayed in the previous version **502**. These features **514** are exemplary of model details that can be added by an operator using the polygonal mesh **402** as a visual reference for portraying features not evident in the point cloud **404** or well segmented in the initial vector model **502**.

The end product of an embodiment is shown in FIG. **5c**, it is a schematic structural report for roof repair **520**. The report **520** is principally composed of a schematic dimensioned design plan diagram **522** and a list of components or construction takeoff list **524** attributed with construction relevant parameters including type, overall area or length, pitch (or facet slope). The report design plan diagram **522** or component list **524** may also include attributed annotations **308** that were optionally specified by users with the example image inspection interface **302** shown in FIG. **3**. The structural report **520** can also contain other industry standard components such as example aerial oblique images of the structure labeled by canonical camera direction that are not shown in FIG. **5c**.

Description FIG. **6**—Image Processing Workflow. FIG. **6** provides a method workflow diagram **600** for an image

processing method of an embodiment whereby a structural model is generated from UAV imagery and is in turn used for generating a report **520** suitable for estimating cost of construction or repair. Portions of the report **520** can be automatically updated if, for example, the enterprise user **112**, field user **100**, or internal algorithm provides additional information via the image inspection service **113** to be added to the report **520** at a later time. The process begins with the Structure Model Generator **109** retrieving a collection of images with their respective geotags and a nominal camera model from the Image Database **108** and performing standard image matching to solve for a photogrammetric bundle adjustment **602**, where camera intrinsic and orientation parameters are estimated based on triangulating image tie points. The image geotags from the UAV **102** will contain various three-dimensional position errors in excess of several meters and orientation errors of ten degrees. However, these errors will be robustly corrected by bundle adjustment performed with industry standard photogrammetry products such as Pix4D Pix4Dmapper, Agisoft PhotoScan, or VisualSFM because the imagery has been collected with sufficient redundancy and geometric disparity that errors from a plurality of sources and directions can be corrected.

In some embodiments, an optional step **604** which calls for the scale of the adjustment to be modified based on portable calibration targets **212** is included if a higher degree of model accuracy is needed. This process can correct remaining systematic reconstruction scale errors in three dimensions by scaling the modeled distance between two or more calibration targets that are precisely identifiable in two or more images and that are located a known distance apart from one another.

In the next step **606**, the three-dimensional point cloud **404** is generated with a dense correlation matching algorithm and a polygonal mesh **402** is in turn generated from the point cloud **404** with the aforementioned standard photogrammetry products.

In the next step **610**, the point cloud **404** is input to a robust planar or conic section fit algorithm in order to create an initial structural vector model **502**. Some segmentation of the point cloud **404** may be applied with standard interactive point cloud edit tools prior to generating the vector model **502** in order to reduce processing time and minimize extraneous geometry in the scene that is not part of the structure such as from ground or vegetation surfaces.

The vector model **502** can be computed from point cloud **404** using clustering algorithms such as the adaptive RANSAC (Random Sample Consensus), J-Linkage, randomized Hough transform, or the like. This representation would be sufficient in some embodiments for providing an approximate area or slope estimate of selected facets. This automated clustering step is a substantial labor saving technique inherent in this invention and although it has been presented in some references for generating buildings vector models **502** from point clouds **404** created from much more expensive and labor intensive acquisition methods such as terrestrial laser scanners or aerial LIDAR, its applicability to automated UAV acquisition, especially from safe, portable, and widely available automated UAVs, is unexpectedly effective.

A vector cleaning step **610** can be applied next where the facets of the initial structural vector model **502** are regularized with algorithms such as Ramer-Douglas-Peucker algorithm (RDP), Sleeve, Minimum Description Length (MDL), or the like. Such regularization algorithms can be easily constrained to exploit construction domain specific conventions such as maintaining edges to be perfectly horizontal or

vertical, mutually coplanar, and join at angles that are modulo 7.5 degrees. When applied to successive facets, nearby vertices can be joined in order to maintain a so called watertight vector model **510** without interior gaps between adjacent facets. Extraneous facets **504** can be eliminated

algorithmically based on area, perimeter, and surface normal thresholds or through interactive editing. Embodiments using interactive editing for this process **610** can display the polygonal mesh **402** for the operator to use as a visual reference in order to verify the model portrays needed features seen in the imagery. The small roof protrusions **514** are examples of features that can be corrupted or omitted during the reconstruction **606** or model fit processes **608** but that can be restored with manual editing during creation of the regularized vector model **610** using standard solid geometry operations with a CAD package such as Autodesk Revit, Bentley MicroStation, or Trimble SketchUp. In some embodiments, machine learning techniques such as Convolutional Neural Networks can be combined with segmentation techniques such as Conditional Random Fields in order to detect and segment features that need to be either included or removed from vector models such as roof vents, chimneys, windows, trees, or power lines.

Another processing step of one embodiment is to create a report **520** with data suitable to estimate a needed construction task **612**, or for other purposes. This process, may be performed by the Structure report engine **110**, and uses the regularized vector model **510** as input and annotates it with descriptive information such as dimensions and selected inspection annotations **308** stored in the structure database **107** to form a report design plan diagram **522**.

Another useful component of the structure report **520** is the construction takeoff list **524**. Components of this list **524** can be attributed automatically from the vector model **510** geometric topology. For example, exterior wall facets are vertically oriented, roof facets are horizontal (flat) or pitched, roof eaves are horizontal edges at the bottom of roof facets, whereas roof ridges are horizontal edges at the top of roof facets. The facet edge classifications can be made within tolerances to accommodate systematic tilts of few degrees within the reconstruction due to GNSS errors.

Robust methods can then be used to eliminate the systematic tilts of the three dimensional models (**402**, **404**, and **510**) based on building construction conventions that maintain level structures to within a fraction of a degree by calculating the average or median tilt angles of various labeled edges in the vector model **510** and subtracting those tilt vectors from the models (**402**, **404**, and **510**).

Roof repair cost estimates are a function of various facet and edge attributes such as area, length, pitch, type, etc. that are listed in the takeoff list **524** and can be transferred to industry standard construction estimation software such as Xactware Xactimate. Finally, enterprise users **112** are notified **614** when the finished structure report **520** is posted to the Structure Database **107**. However, in some embodiments, structural modeling steps (**608**, **610**, **612**, and **614**) can be omitted for use cases where the photo textured polygonal mesh **402** or a structural vector model **502** is the desired output.

FIG. 7 illustrates a monitoring computing environment **700** according to one example. Computing environment **700** includes computing system **710** and computing system **750**. Computing system **710**, in the present example, corresponds to mobile device **101**, and computing system **750** corresponds to server **160**. Computing system **710** can include any smart phone, tablet computer, laptop computer, or other

computing or mobile device capable of reading, and/or recording data about systems, devices, locations, and/or equipment, etc. Computing system **750** can include any server computer, desktop computer, laptop computer, or other device capable of storing and managing the data collected by computing system **710** or other similar computing systems. Either system **710** or **750** can be capable of accomplishing any of the steps of functions described in this description.

In FIG. 7, computing system **710** includes processing system **716**, storage system **714**, software **712**, communication interface **718**, and user interface **720**. Processing system **716** loads and executes software **712** from storage system **714**, including software module **740**. When executed by computing system **710**, software module **740** directs processing system **716** to receive data, images, devices, locations, and/or equipment, etc. Such data could include any of the information described above, including but not limited to the functionality described for FIGS. 1-6.

Although computing system **710** includes one software module in the present example, it should be understood that one or more modules could provide the same operation. Similarly, the computing systems may be distributed using other computing systems and software.

Additionally, computing system **710** includes communication interface **718** that can be further configured to transmit the collected data to computing system **750** using communication network **705**. Communication network **705** could include the Internet, cellular network, satellite network, RF communication, blue-tooth type communication, near field, or any other form of communication network capable of facilitating communication between computing systems **710** and **750**. In some examples, communication interface **718** can further include a global positioning system to determine the location of computing system **710**.

Referring still to FIG. 7, processing system **716** can comprise a microprocessor and other circuitry that retrieves and executes software **712** from storage system **714**. Processing system **716** can be implemented within a single processing device but can also be distributed across multiple processing devices or sub-systems that cooperate in executing program instructions. Examples of processing system **716** include general purpose central processing units, application specific processors, and logic devices, as well as any other type of processing device, combinations of processing devices, or variations thereof. Storage system **714** can comprise any storage media readable by processing system **716**, and capable of storing software **712**. Storage system **714** can include volatile and nonvolatile, removable and non-removable media implemented in any method or technology for storage of information, such as computer readable instructions, data structures, program modules, or other data. Storage system **714** can be implemented as a single storage device but may also be implemented across multiple storage devices or sub-systems. Storage system **714** can comprise additional elements, such as a controller, capable of communicating with processing system **716**.

Examples of storage media include random access memory, read only memory, magnetic disks, optical disks, flash memory, virtual memory, and non-virtual memory, magnetic cassettes, magnetic tape, magnetic disk storage or other magnetic storage devices, or any other medium which can be used to store the desired information and that may be accessed by an instruction execution system, as well as any combination or variation thereof, or any other type of storage media. In some implementations, the storage media can be a non-transitory storage media. In some implemen-

tations, at least a portion of the storage media may be transitory. It should be understood that in no case is the storage media a propagated signal. Although one software module is shown, the software may be distributed across many devices, storage media, etc.

User interface **720** can include a mouse, a keyboard, a camera, image capture, a voice input device, a touch input device for receiving a gesture from a user, a motion input device for detecting non-touch gestures and other motions by a user, and other comparable input devices and associated processing elements capable of receiving user input from a user. These input devices can be used for defining and receiving data about the location, maps, systems, devices, locations, and/or equipment, etc. Output devices such as a graphical display, speakers, printer, haptic devices, and other types of output devices may also be included in user interface **720**. The aforementioned user input and output devices are well known in the art and need not be discussed at length here.

Application interface **730** can include data input **735** and image display **737**. In one example, data input **735** can be used to collect information regarding the location, property boundaries, UAV, maps, etc. It should be understood that although computing system **710** is shown as one system, the system can comprise one or more systems to collect data.

Computing system **750** includes processing system **756**, storage system **754**, software **752**, and communication interface **758**. Processing system **756** loads and executes software **752** from storage system **754**, including software module **760**. When executed by computing system **750**, software module **760** directs processing system **710** to store and manage the data from computing system **710** and other similar computing systems. Although computing system **710** includes one software module in the present example, it should be understood that one or more modules could provide the same operation.

Additionally, computing system **750** includes communication interface **758** that can be configured to receive the data from computing system **710** using communication network **705**.

Referring still to FIG. 7, processing system **756** can comprise a microprocessor and other circuitry that retrieves and executes software **752** from storage system **754**. Processing system **756** can be implemented within a single processing device but can also be distributed across multiple processing devices or sub-systems that cooperate in executing program instructions. Examples of processing system **756** include general purpose central processing units, application specific processors, and logic devices, as well as any other type of processing device, combinations of processing devices, or variations thereof.

Storage system **754** can comprise any storage media readable by processing system **756**, and capable of storing software **752** and data from computing system **710**. Data from computing system **710** may be stored in a word, excel, or any other form of digital file. Storage system **754** can include volatile and nonvolatile, removable and non-removable media implemented in any method or technology for storage of information, such as computer readable instructions, data structures, program modules, or other data. Storage system **754** can be implemented as a single storage device but may also be implemented across multiple storage devices or sub-systems. Storage system **754** can comprise additional elements, such as a controller, capable of communicating with processing system **756**.

Examples of storage media include random access memory, read only memory, magnetic disks, optical disks,

flash memory, virtual memory, and non-virtual memory, magnetic cassettes, magnetic tape, magnetic disk storage or other magnetic storage devices, or any other medium which can be used to store the desired information and that may be accessed by an instruction execution system, as well as any combination or variation thereof, or any other type of storage media. In some implementations, the storage media can be a non-transitory storage media. In some implementations, at least a portion of the storage media may be transitory. It should be understood that in no case is the storage media a propagated signal.

In some examples, computing system **750** could include a user interface. The user interface can include a mouse, a keyboard, a voice input device, a touch input device for receiving a gesture from a user, a motion input device for detecting non-touch gestures and other motions by a user, and other comparable input devices and associated processing elements capable of receiving user input from a user. Output devices such as a graphical display, speakers, printer, haptic devices, and other types of output devices may also be included in the user interface. The aforementioned user input and output devices are well known in the art and need not be discussed at length here. It should be understood that although computing system **750** is shown as one system, the system can comprise one or more systems to store and manage received data.

The included descriptions and figures depict specific implementations to teach those skilled in the art how to make and use the best mode. For the purpose of teaching inventive principles, some conventional aspects have been simplified or omitted. Those skilled in the art will appreciate variations from these implementations that fall within the scope of the invention. Those skilled in the art will also appreciate that the features described above can be combined in various ways to form multiple implementations. As a result, the invention is not limited to the specific implementations described above, but only by the claims and their equivalents.

What is claimed is:

1. An image and information capturing and processing system, comprising:

a mobile computing device configured to:

receive user input data and/or third party data at the mobile computing device;

create unmanned aerial vehicle control data based at least in part on the user input data and/or the third party data; create a flight plan based at least in part on the unmanned aerial vehicle control data comprising a generally crude outline of a structure area of interest to insure images and data capturing are taken at optimal distances and intervals for three-dimensional reconstruction and visual inspection;

transmit the flight plan to an unmanned aerial vehicle via a communication link;

execute the flight plan at least in part by issuing commands to flight and camera controllers of the unmanned aerial vehicle, wherein the commands comprise an orbit at calculated ranges with a specified minimum depression angle to insure complete image coverage of the structure area of interest from each perspective, omnidirectional orbital imaging capable of reducing obstructions for inspection and three-dimensional reconstruction of the structure of interest in order to allow three-dimensional point cloud reconstruction;

receive unmanned aerial vehicle output data from the unmanned aerial vehicle; and

transmit the unmanned aerial vehicle output data to a server via a wireless or wired communication link, wherein the unmanned aerial vehicle output data comprises highly redundant imagery with full generality of structural shape, height, obstructions, and operator error, which generally requires no topographical aerial image data, that can be used to generate a three-dimensional structural reconstruction that is accurately scaled in three dimensions with less than one-percent systematic relative error with or without GPS/GNSS; wherein the unmanned aerial vehicle output data comprises information used to create a point cloud density over an entire structure area of interest, which is substantially uniform ranging from 100-10,000 points per square meter while retaining at least two centimeters vertical precision, that can be converted into a regularized vector model of the structure area of interest.

2. The system of claim 1, further comprising a server configured to:

receive the transmitted unmanned aerial vehicle output data, wherein the unmanned aerial vehicle output data comprises reliable geotagged images of a structure area of interest and global positioning system information, comprising highly redundant imagery with full generality of structural shape, height, obstructions, and operator errors, which requires no a priori topographic or aerial image data, that can be used to generate a reconstruction accurately scaled in three dimensions with less than one percent systematic relative error with or without GPS/GNSS;

store the modified unmanned aerial vehicle data in an image database;

generate a three-dimensional photogrammetric point cloud density over the entire structure area of interest, which is substantially uniform ranging from 100-10,000 points per square meter while retaining at least two centimeters vertical precision, that can be converted into the regularized vector model of the structure area of interest, wherein the three-dimensional photogrammetric point cloud density is generated based at least in part on the received modified unmanned aerial vehicle data;

reconstruct surface points using dense matching algorithms to correlate neighboring images with a sufficiently low angular separation, with minimal point cloud voids even with limited surface texture, which allows three-dimensional reconstruction and image inspection to be complete despite obstructions occluding portions of the structural area of interest in at least some of the geotagged images; and

create three-dimensional regularized vector models using the point cloud model and regularization algorithms.

3. The system of claim 1, wherein the flight plan comprises a launch or home location, property bounds, a crude outline of the structure area of interest, structure height, and the obstacle clearance height.

4. The system of claim 3, wherein the home location comprises the global positioning system location of where the unmanned aerial vehicle is initialized, will launch from, and will land near.

5. The system of claim 1, wherein the third party data comprises geographic or property information from public or commercially available databases based at least in part on the property mailing address or geolocation.

6. The system of claim 1, wherein the unmanned aerial vehicle control data comprises a flight plan for the

unmanned aerial vehicle comprising an obstacle free launch trajectory and an acquisition trajectory.

7. The system of claim 6, wherein the flight plan is executed by issuing commands to the unmanned aerial vehicle's flight and camera controller at least in part via the unmanned aerial vehicle's application program interface, to traverse a series of geographic waypoints, capture images in orientations ensuring substantially complete coverage of the structure area of interest, and record camera position and orientation, wherein the flight plan, when paused, allows the field user to manually control the unmanned aerial vehicle to capture supplemental images of interest before resuming the flight plan.

8. The system of claim 1, wherein the unmanned aerial vehicle control data comprises commands for image capturing at camera exposure stations along the acquisition trajectory such that successive images are angularly separated by less than an angle θ with respect to the centroid of the structure area of interest, and wherein the camera at each exposure station is generally orthogonal to the acquisition trajectory such that the unmanned aerial vehicle's camera gimbal does not require yaw steering control.

9. The system of claim 8, wherein the unmanned aerial vehicle control data comprises two geometric transformation algorithms that use the input data, third party data or data about the structure area of interest to ensure that the camera exposure stations enable three-dimensional reconstruction of the structure area of interest, wherein

a convex hull is computed, eliminating concavities in the trajectory which could lead to diverging perspectives and reduced overlap or low parallax displacement between successive exposures; and

a dilation operation is applied to maintain adequate range so that the entire structure area of interest is contained within each image field of view, wherein photos are captured at intervals along the acquisition trajectory to insure that the angular separation between camera exposures does not exceed an angle θ that would reduce image match accuracy but also minimizes the total number of images required.

10. The system of claim 1, wherein the unmanned aerial vehicle output data comprises, at least in part, geotagged images of the structure area of interest, GPS/GNSS information, or calibration targets deployed to accurately scale a three-dimensional structure model.

11. The system of claim 1, wherein the unmanned aerial vehicle output data is generally immediately made available to a server to assure accuracy of the unmanned aerial vehicle data and to facilitate rapid remote inspection of the structure area of interest.

12. The system of claim 1, wherein the unmanned aerial vehicle output data is limited to the structure area of interest and eliminates or degrades imagery of objects or people outside the property bounds based on an image mask derived from the three-dimensional reconstruction polygon mesh and the property boundary.

13. A method of capturing and processing automated images comprising:

receiving the transmitted unmanned aerial vehicle output data by a server, wherein the unmanned aerial vehicle output data comprises reliable geotagged images of a structure area of interest and global positioning system information, comprising highly redundant imagery with full generality of structural shape, height, obstructions, and operator errors, which requires no a priori topographic or aerial image data, that can be used to

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generate a regularized vector model accurately scaled in three dimensions with less than one percent systematic relative error;

storing the modified unmanned aerial vehicle data in an image database on the server;

generating a three-dimensional photogrammetric point cloud density by the server over the entire structure area of interest, which is substantially uniform ranging from 100-10,000 points per square meter while retaining at least two centimeters vertical precision, that can be converted into a regularized vector model of the structure area of interest, wherein the three-dimensional photogrammetric point cloud density is generated based at least in part on the received modified unmanned aerial vehicle data;

reconstructing surface points using dense matching algorithms on a server to correlate neighboring images with a sufficiently low angular separation and minimal point cloud voids, even with limited surface texture, which allows three-dimensional reconstruction and image inspection to be complete despite obstructions occluding portions of the structural area of interest in at least some of the fully redundant set geotagged images; and creating three-dimensional regularized vector models using the point cloud model and regularization algorithms.

14. The method of claim 13, wherein the unmanned aerial vehicle output data comprises precise visual reference images based on captured images, which are a generally exact orthographical projection, containing image features that are not shifted by a parallax based on their elevation.

15. The method of claim 13, further comprising a structure model generator, on the server, configured to perform initial quality checks on the modified unmanned aerial vehicle data to verify the modified unmanned aerial vehicle data is usable, and wherein the structure model generator issues a notification if the modified unmanned aerial vehicle data needs to be reacquired.

16. The method of claim 14, wherein the structure model generator retrieves a collection of images with corresponding geotags, and a nominal camera model from the image database, and performs image matching to solve for a photogrammetric bundle adjustment, dense matching, and vector surface fitting.

17. The method of claim 15, wherein the structure model generator performs vector cleaning, wherein facets of the initial structural vector model are regularized with algorithms to create a regularized watertight vector model with edges labeled according to their topology and construction conventions.

18. The method of claim 16, wherein facet edge classifications can be made within tolerances to accommodate

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systematic tilts of a few degrees with the three-dimensional reconstruction process due to GNSS errors.

19. The method of claim 17, wherein the structure model generator creates a report with data suitable to estimate a needed task by the structure report engine, wherein the structure report engine uses the regularized vector model as input, and annotates the regularized vector model with descriptive information, wherein the descriptive information comprises dimensions and selected inspection annotations stored in the structure database, to form a report design plan diagram, and wherein the report design plan diagram is published into a structure database and is capable of being retrieved by an enterprise user or other users along with other three dimensional data products available for self annotation, interactive measurement, and report modification.

20. A non-transitory computer readable medium with instructions stored thereon which, if executed by a processor, causes the processor to:

receive the transmitted unmanned aerial vehicle output data by a server, wherein the unmanned aerial vehicle output data comprises reliable geotagged images of an area of interest and global positioning system information, comprising highly redundant imagery with full generality of structural shape, height, obstructions, and operator errors, which requires no a priori topographic or aerial image data, that can be used to generate a reconstruction accurately scaled in three dimensions with less than one percent systematic relative error; store the modified unmanned aerial vehicle data in an image database on the server;

generate a three-dimensional photogrammetric point cloud by the server over the entire area of interest, which is substantially uniform ranging from 100-10,000 points per square meter while retaining at least two centimeters vertical precision, that can be converted into a regularized vector model of the area of interest, wherein the three-dimensional photogrammetric point cloud density is generated based at least in part on the received modified unmanned aerial vehicle data;

reconstruct surfaces of the area of interest using dense matching algorithms on a server to correlate neighboring images with a sufficiently low angular separation and minimal point cloud voids, even with limited surface texture, which allows three-dimensional reconstruction and image inspection to be complete despite obstructions occluding portions of the structural area of interest in at least some of the geotagged images; and create three-dimensional regularized vector models using the point cloud model and regularization algorithms.

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