




Quality Report

PIX4Dmatic v2.0.0



Camera	Skydio_VT300L93_7.7_8192x6144
Area covered	5.020 ha
Average GSD	1.5 cm
Project CRS	WGS 84 / UTM zone 10N - EPSG:32610

Quality check

Matches	Median of 7109 matches per calibrated image	
Dataset	100% calibrated (43/43 images), 1 calibration block	
Camera optimization	4.57% relative difference between initial and optimized internal camera parameters	
ATPs	108755 ATPs	

Cameras



Internal camera parameters

Skydio_VT300L93_7.7_8192x6144. Sensor dimensions: 13.107 mm x 9.83 mm

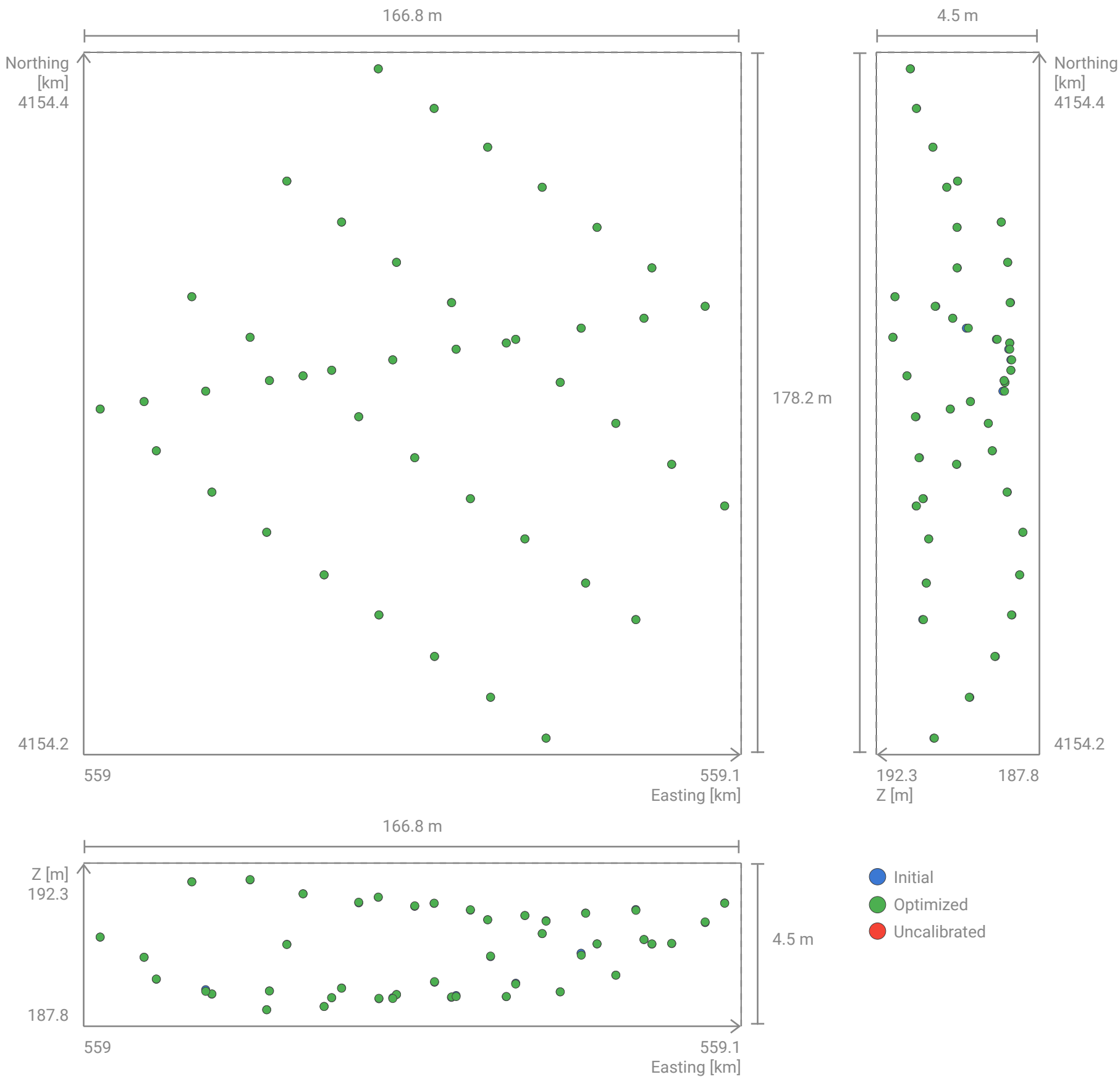
	Focal length	Principal point x	Principal point y	R1	R2	R3	T1	T2
Initial	4837.5 px 7.74 mm	4096.0 px 6.554 mm	3072.0 px 4.915 mm	0.0021229	0.0470915	-0.0513749	0.0000000	0.0000000
Optimized	5058.5 px 8.094 mm	4046.8 px 6.475 mm	3061.6 px 4.899 mm	0.0019121	0.0685386	-0.0657817	0.0004957	0.0003085
Uncertainties (Sigma)	0.1 px <0.001 mm	<0.1 px <0.001 mm	<0.1 px <0.001 mm	<0.0000001	0.0000002	0.0000001	<0.0000001	<0.0000001

Absolute geolocation variance



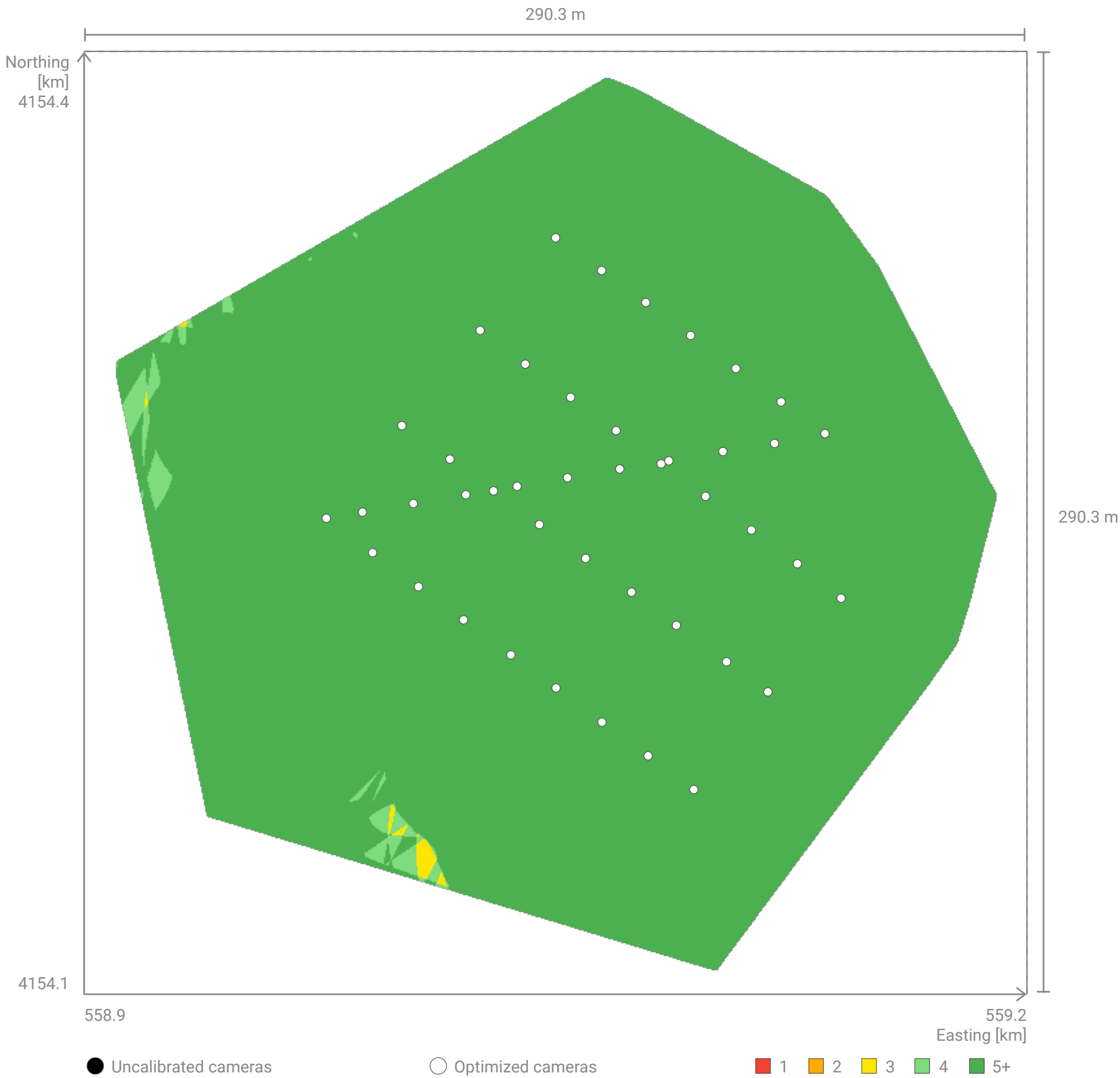
The geolocation error is the difference between the initial and computed camera positions. Plots show the per-axis distributions of geolocation errors across the cameras. Large positive and negative errors are denoted with the orange bins. Note that the image geolocation errors do not correspond to the accuracy of the observed 3D points.

Camera positions



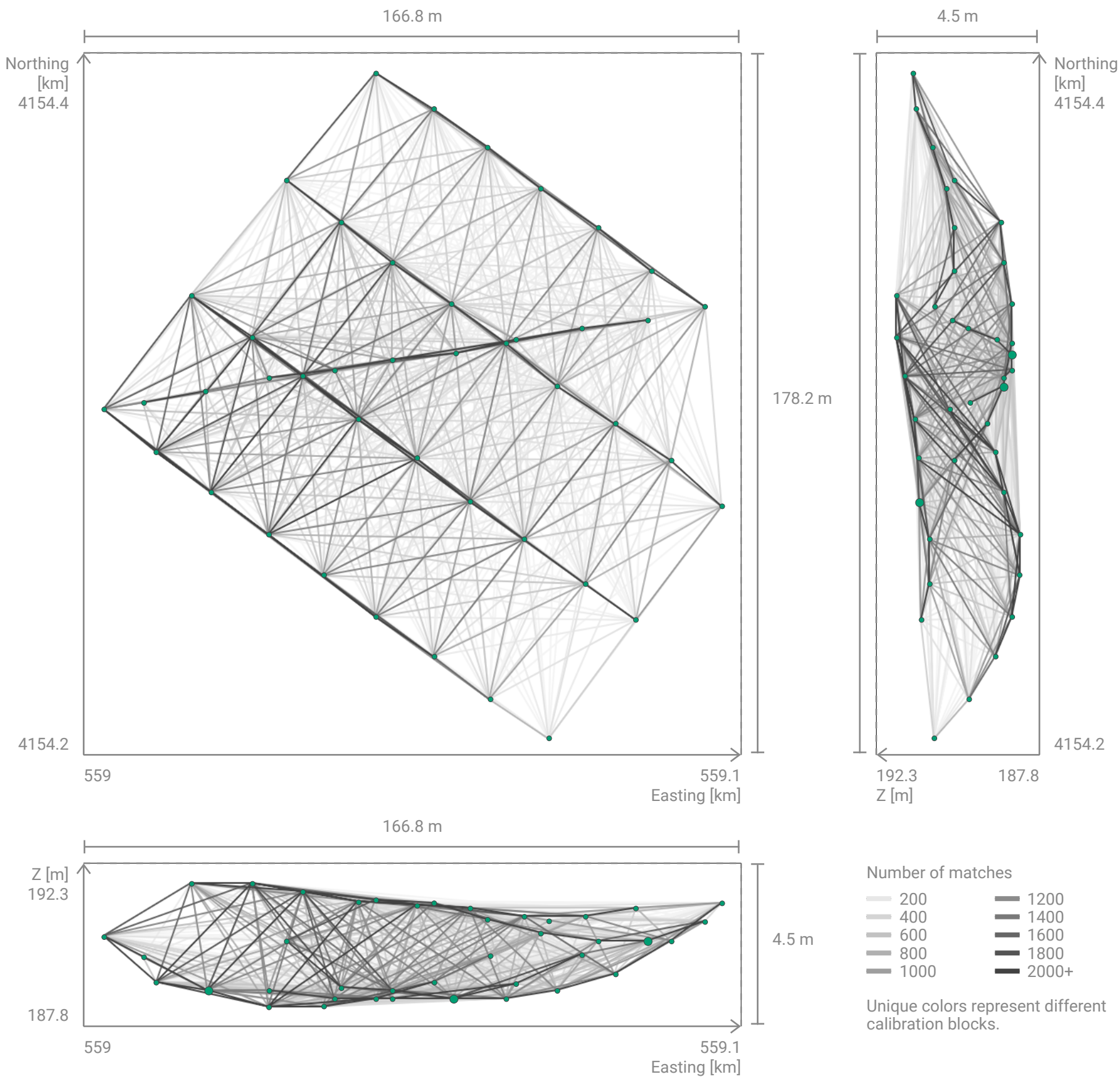
Initial and computed camera positions.

Overlap



This graph shows the number of overlapping images for each pixel of the DSM preview. For precise 3D modeling and mapping applications, the overlap should be in green, i.e. each pixel should be visible in more than 5 images.

2D Keypoint matches



Computed camera positions with links between matched cameras. The opacity of the links indicates the number of matched 2D keypoints between the cameras. Near-transparent links indicate weak links and require manual tie points or more cameras. To improve visibility, camera positions may be slightly shifted and multiple cameras may be grouped into a single point on the plot. Group of multiple cameras is indicated by a larger point on the plot.

Hardware & Settings



System information

CPU	Apple M4 Max, cpus=1, threads=14
RAM	36 GB
GPU	Apple Apple M4 Max (Driver: 4.1 Metal - 89.3)
Operating system	macOS Sequoia (15.1)

Coordinate reference systems

Image coordinate reference system	WGS 84 - EPSG:4326
Project coordinate reference system	WGS 84 / UTM zone 10N - EPSG:32610

Processing settings

Calibration

Completed

Template: Map

Pipeline: Standard

Image scale: 1

Internals confidence: Low

Externals confidence: Default

Simultaneous camera internals and MTP/GCP optimization: Disabled

Max. extracted keypoints: Automatic

Use automatic ITPs: Disabled

2m 37s