Multi-temporal UAV-survey of a calving glacier in Northwest Greenland

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VGC 2016
Bergen

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Agenda

- Location and motivation Bowdoin Glacier (NW Greenland)
- Requirements, choice, type and assembly of used UAV
- Ground Control Points
- Selection of flight plans
- Some first results
- Summary

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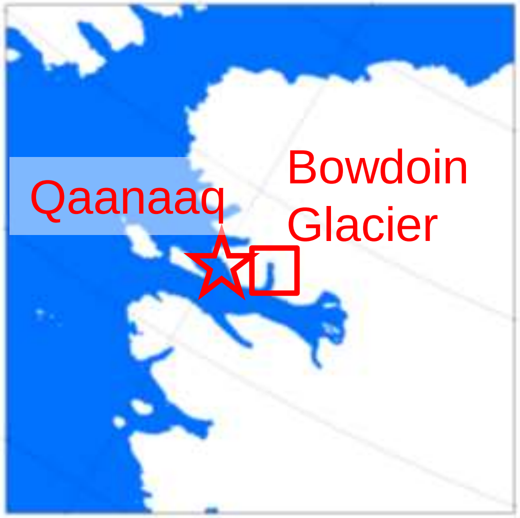
Location Bowdoin Glacier (77° 42’ N; 68° 35’ W)



Motivation Bowdoin Glacier

Science:

- Processes of sea glaciers
- Modell of the calving front

Facts:

- Retreat after 2008
- Installations at the calving front
- Easy access
- 24h daylight

Expeditions 2014, 2015, 2016

- **Participating Universities:**
  - Institute of Low Temperature Science Hokkaido University (Japan)
  - Laboratory of Hydraulics, Hydrology and Glaciology ETH Zurich
- **Various experiments and measurements:**
  - Drilling of 3 boreholes of appr. 300m depth and instrumentation
  - Collection and maintenance of drill sites (water pressure, deformation, temperature)
  - Collection und maintenance of several timelaps cameras
  - Permanent GPS stations (with local reference station)
  - Seismic and Infrasound arrays (on and off glacier)
  - Interferometric terrestrial radar during expedition (2016)
  - **UAV-based surface models and orthophoto mosaics of the calving front (2015 experimental, 2016 productive)**

Requirements for a UAV at Bowdoin

Requirements:

- Flights > 50 kilometres autonomously and out of sight
- Flight height up to 500 meters above ground
- Payload > 0.5 kg to 1.0 kg
- Arctic conditions (wind, camp, no workshop, …)
- Easy to repair, open configuration and documentation

No suitable commercial UAV -> Homemade!

Used framework:

- *Skywalker X8* fix wing (2.1 m wingspan)
- *Pixhawk* Autopilot
- *APM:Plane* und *MissionPlanner* as software base

Choice, type and assembly of used UAV

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The Cryosphere
Open Access

UAV photogrammetry and structure from motion to assess calving dynamics at Store Glacier, a large outlet draining the Greenland ice sheet

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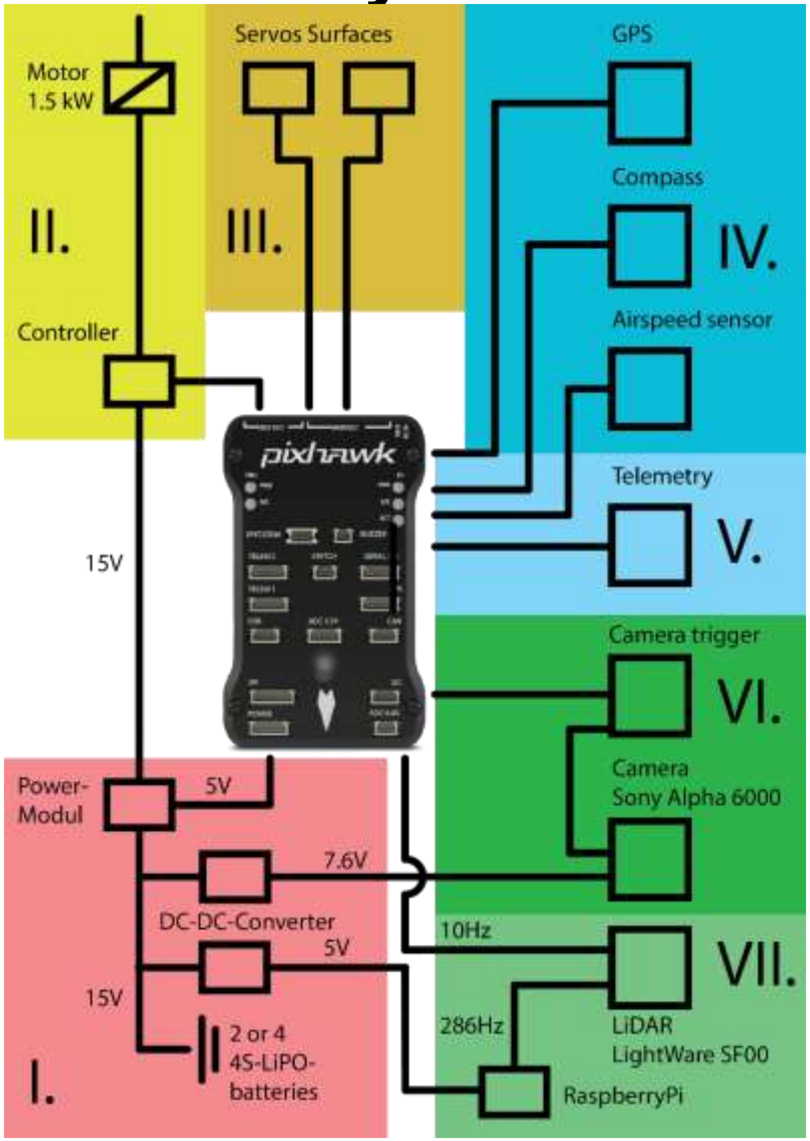
Assembly of the homemade UAV



Fully configurable, inter-exchangeable and open system based on standard components!

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Camera releaser, flexibility, Pixhawk

- **StratoSnapper2, Pixhawk, APM:Plane**
  - Universal camera releaser for most camera models and types
  - Simple and robust, IR- or cable-based
  - Calibration and triggering with servo signal of Pixhawk
  - Individual log entry with X, Y, Z, Roll, Pitch und Yaw
  - `CAM,420509800,1853,77.69099,-68.45031,230.54,31.97,5.64,16.35,244.12`

Choice of camera

- **Sony α6000 E-Mount camera mit APS-C-Sensor**

  Sensor resolution: 24 Megapixel, Raw

  Lens: 16mm, f2.8

  Weight: 344g + 67g (Total ca. 450g)

  IR- and cable-based trigger

- **Sony α7 E-Mount Full-Frame Mirrorless Camera**

  Sensor resolution : 36 Megapixel, Raw

  Lens: 35mm, f2.8

  Weight: 625g + 120g (Total ca. 750g)

  IR- and cable-based trigger

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Requirements UAV flight plans and processing

- **Processing**
  Horizontal resolution <= 10cm ground sampling distance (GSP)
  Vertical resolution <= 50cm (about 3 to 4 times GSP)

- **Image block**
  Overlap along image strip > 85%
  Overlap cross image strip > 70%

➢ **Main flight plan**
  Footprint ca. 270 x 390m -> Flight height 250m above ground
  Horizontal resolution appr. 7cm (GSD)
  Average cruising speed appr. 15m/s
  Distance between images along strip appr. 20m (>= 1sec flight time)
  Distance between image strips appr. 100m

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Ground control points – Types and challenges

- **Stable Ground Control Points (GCP) at both sides of the glacier:**
  - **No stable GCP at the right side of the glacier (2015)**
  - **Many stable GCP at both sides of the glacier (2016)**
- **Moving GCP on glacier**

Ground control points – Moving points

- **Moving GCP on the middle moraine ~ 1 – 2m / day**
- **Permanent GPS stations on the glacier**
- **6 - 8 GPS readings of all GCP on the glacier**
- **Linear interpolation X,Y, Z of GCP for each UAV flight**

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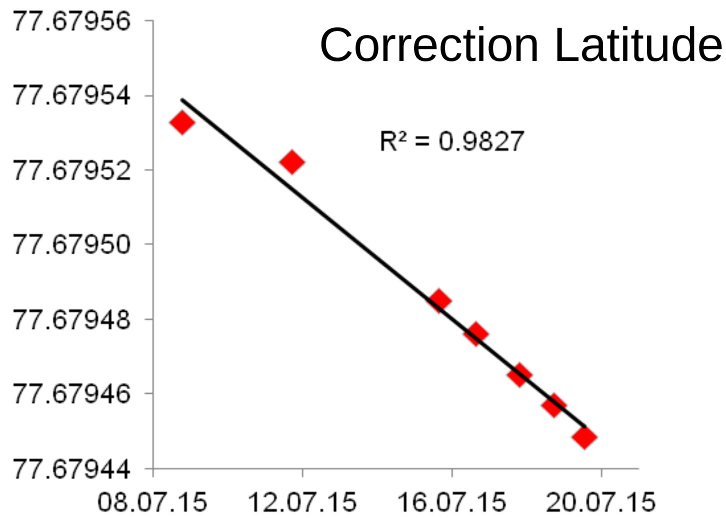
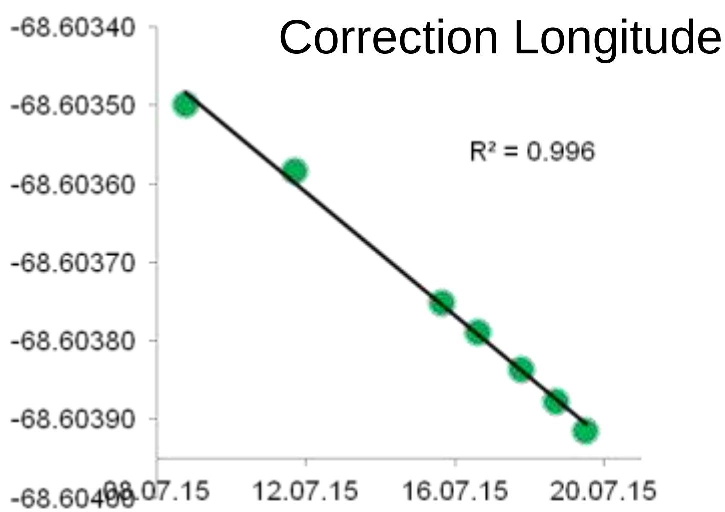
Ground control points – Moving points





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Expedition 2015 vs. 2016 – UAV improvements

- Flights with high temporal resolution (<= 12h) of calving front
- Using of a VTOL for the temporal high resolution flights
- Different flight plans (detailed front, long tracks)
- Longitudinal profiles with nadir-looking LiDAR

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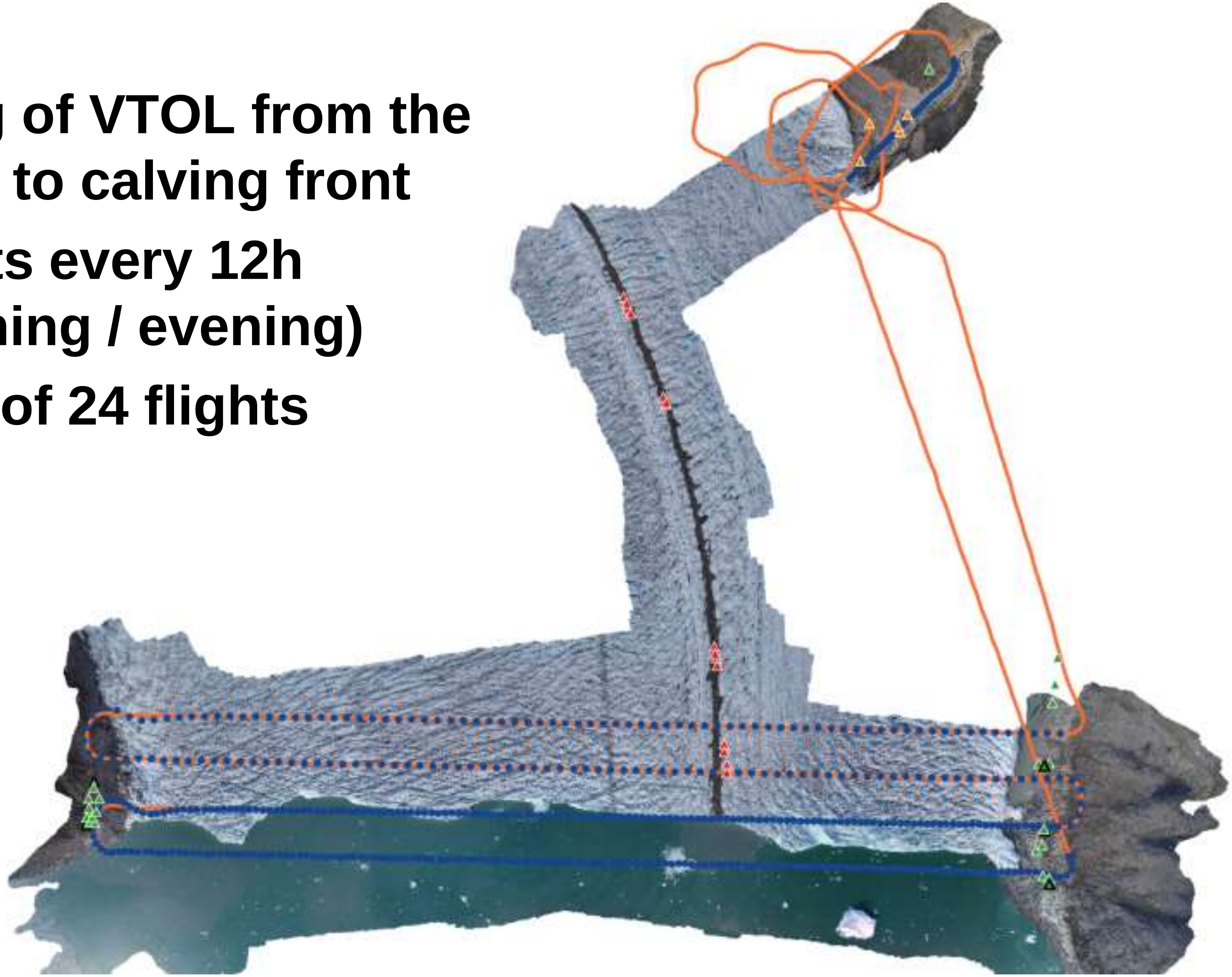
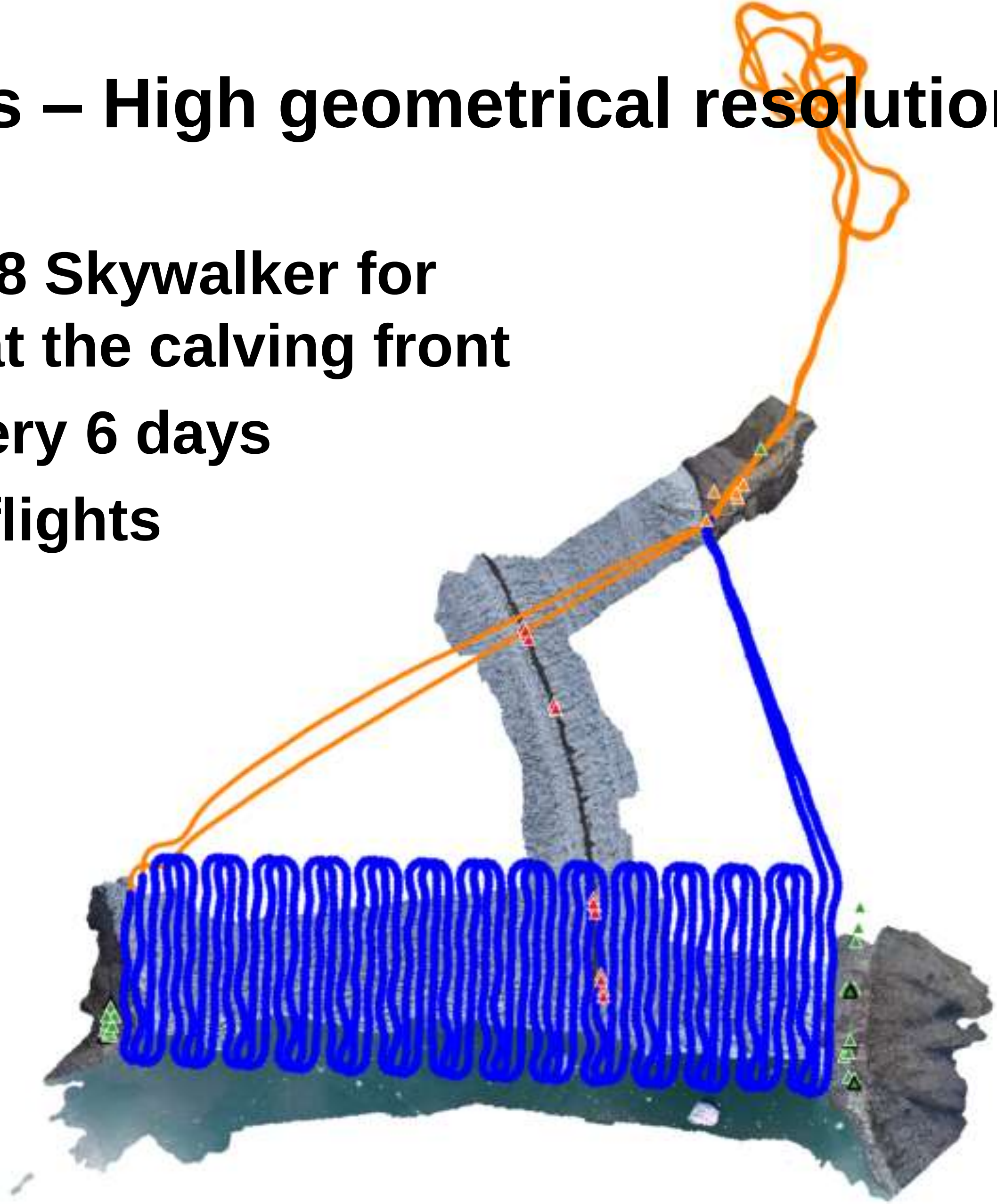
Flight plans – High temporal resolution (<= 12h)

- **Using of VTOL from the camp to calving front**
- **Flights every 12h (morning / evening)**
- **Total of 24 flights**



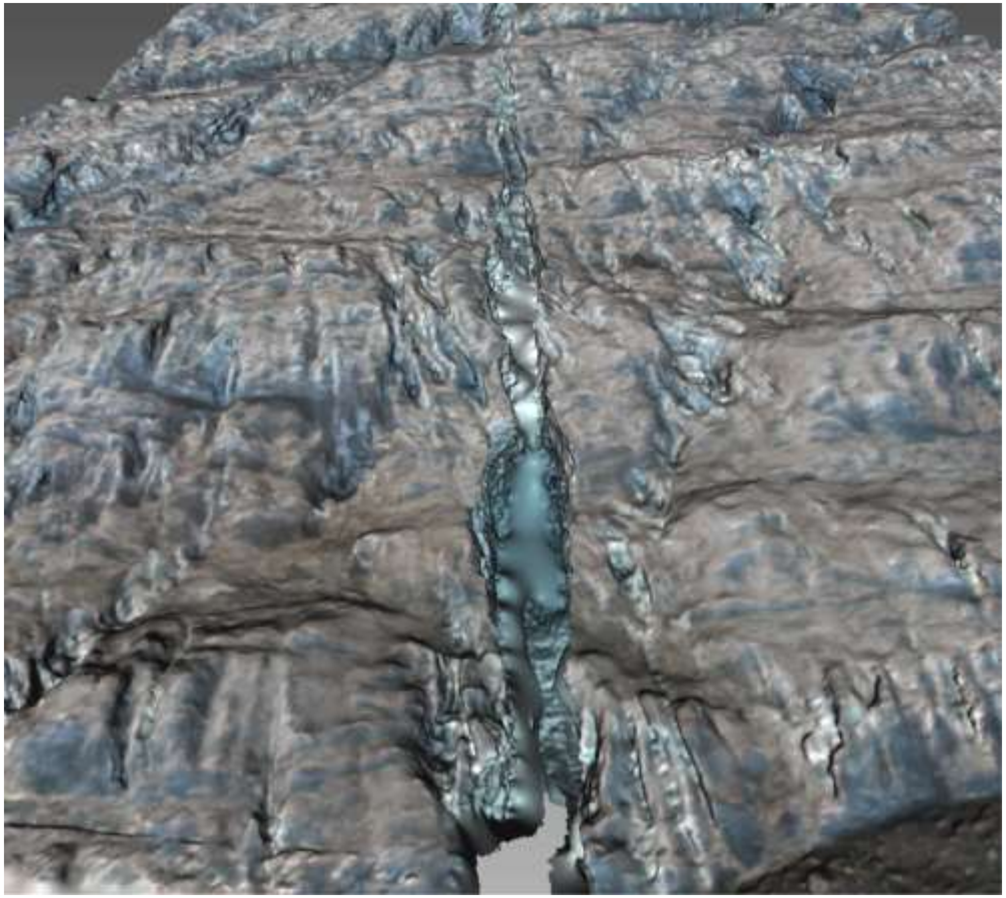
Flight plans – High geometrical resolution

- Using of X8 Skywalker for overview at the calving front
- Flights every 6 days
- Total of 2 flights



Flight plans – High geometrical resolution

- **Quantification and recording of crevasses**

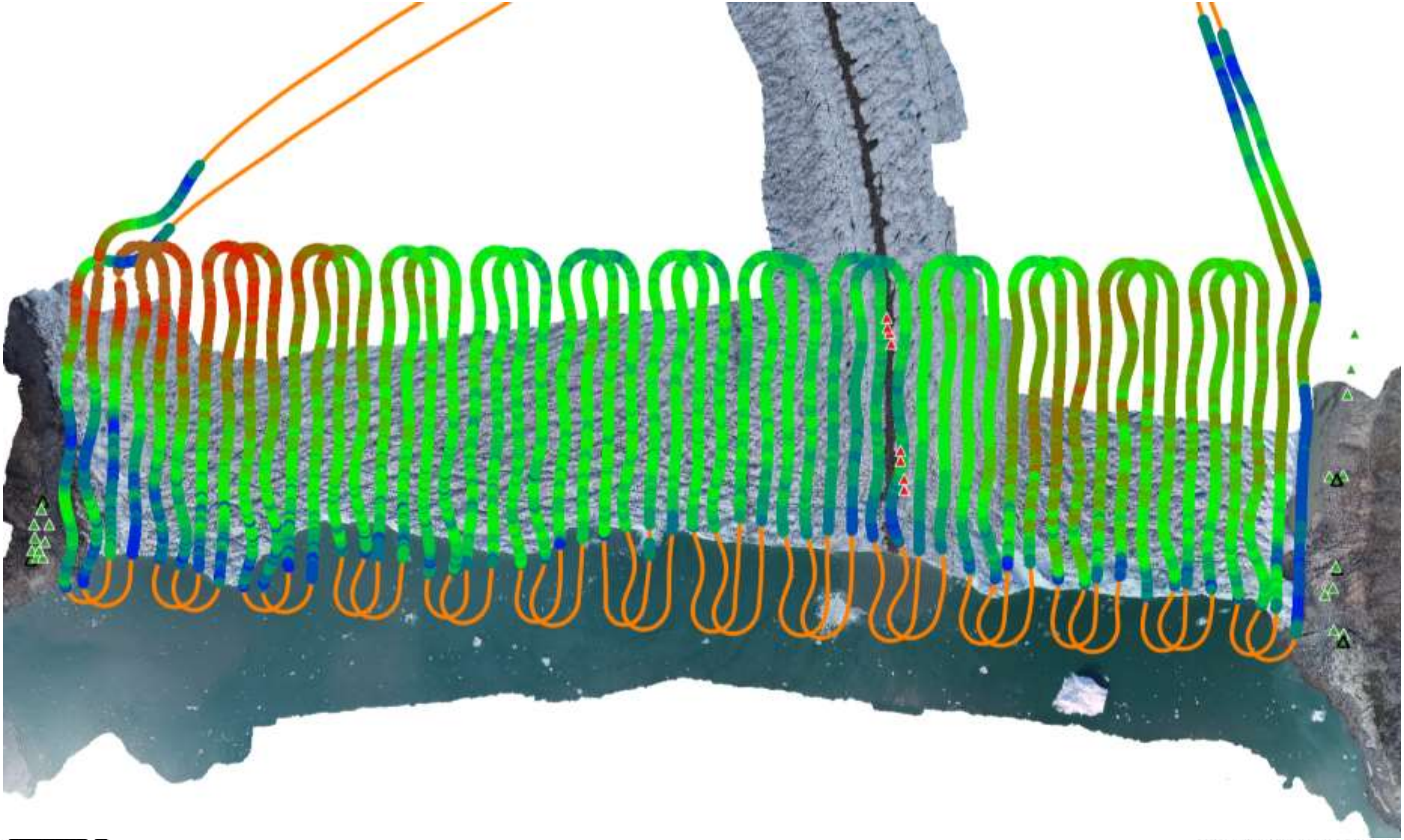


SF00-LiDAR
286 Hz
250 m

Sony
Alpha6000
f = 16 mm

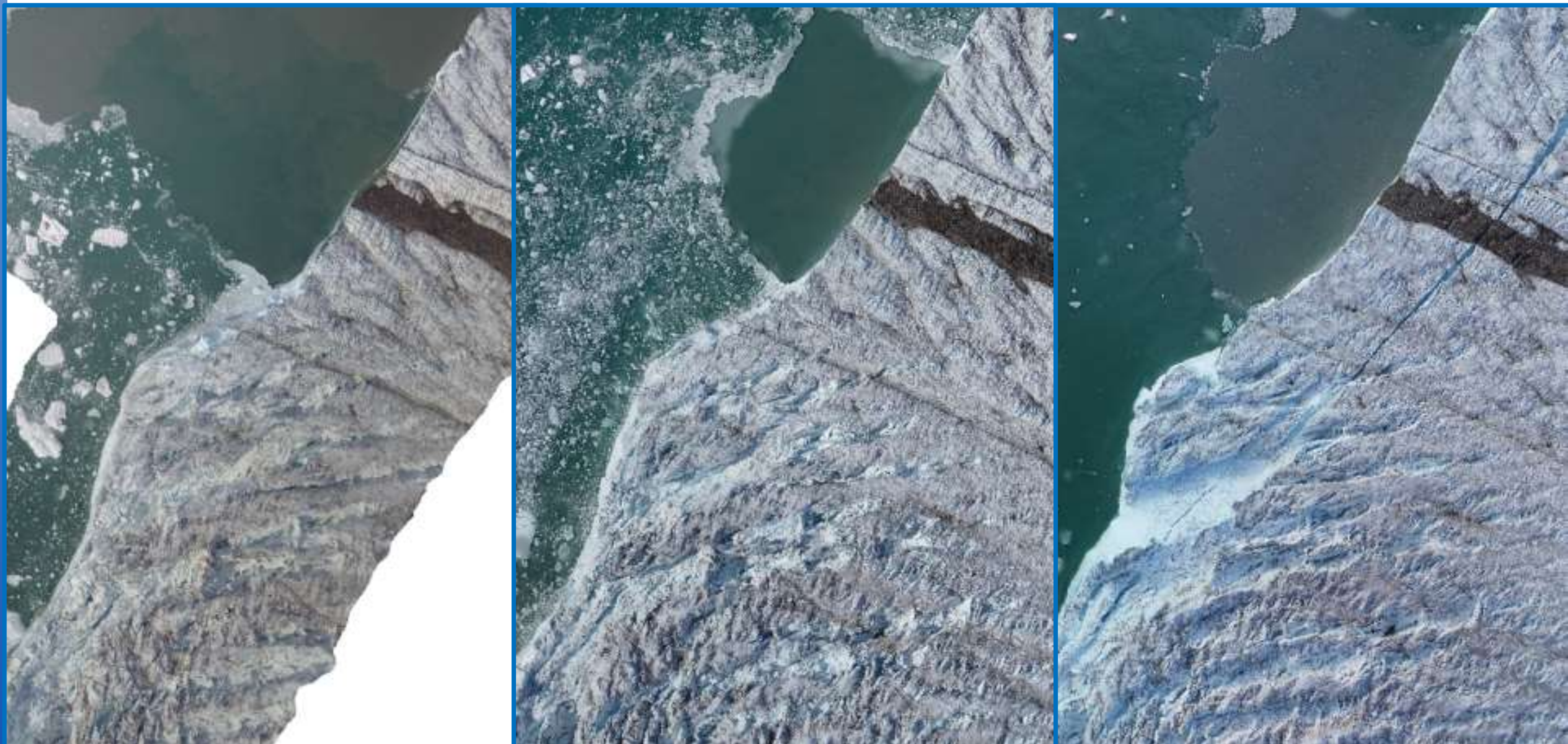
Skywalker X8
Version 2

Flight plans – High geometrical resolution



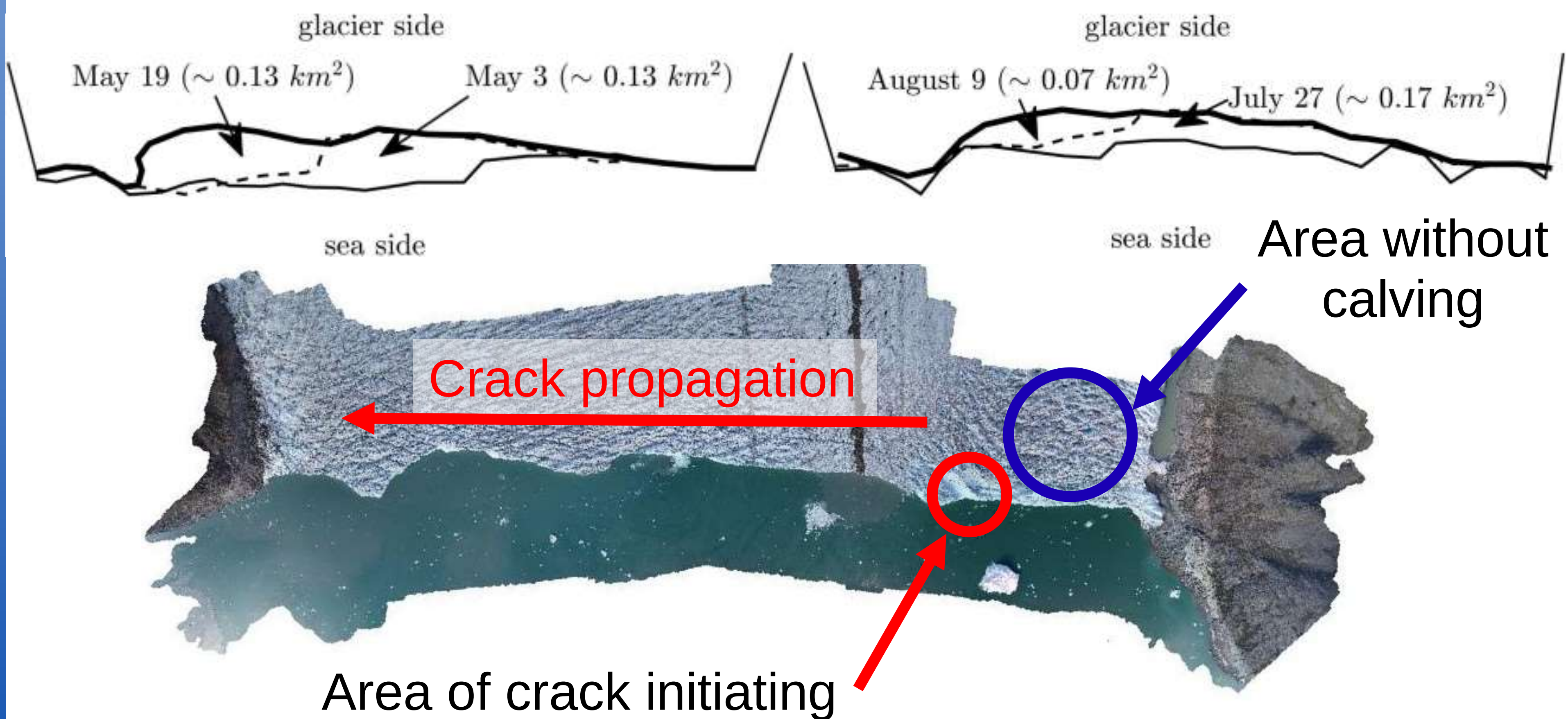
Results – Orthophoto mosaics

July 7th 2015 | July 11th 2015 | July 16th 2015



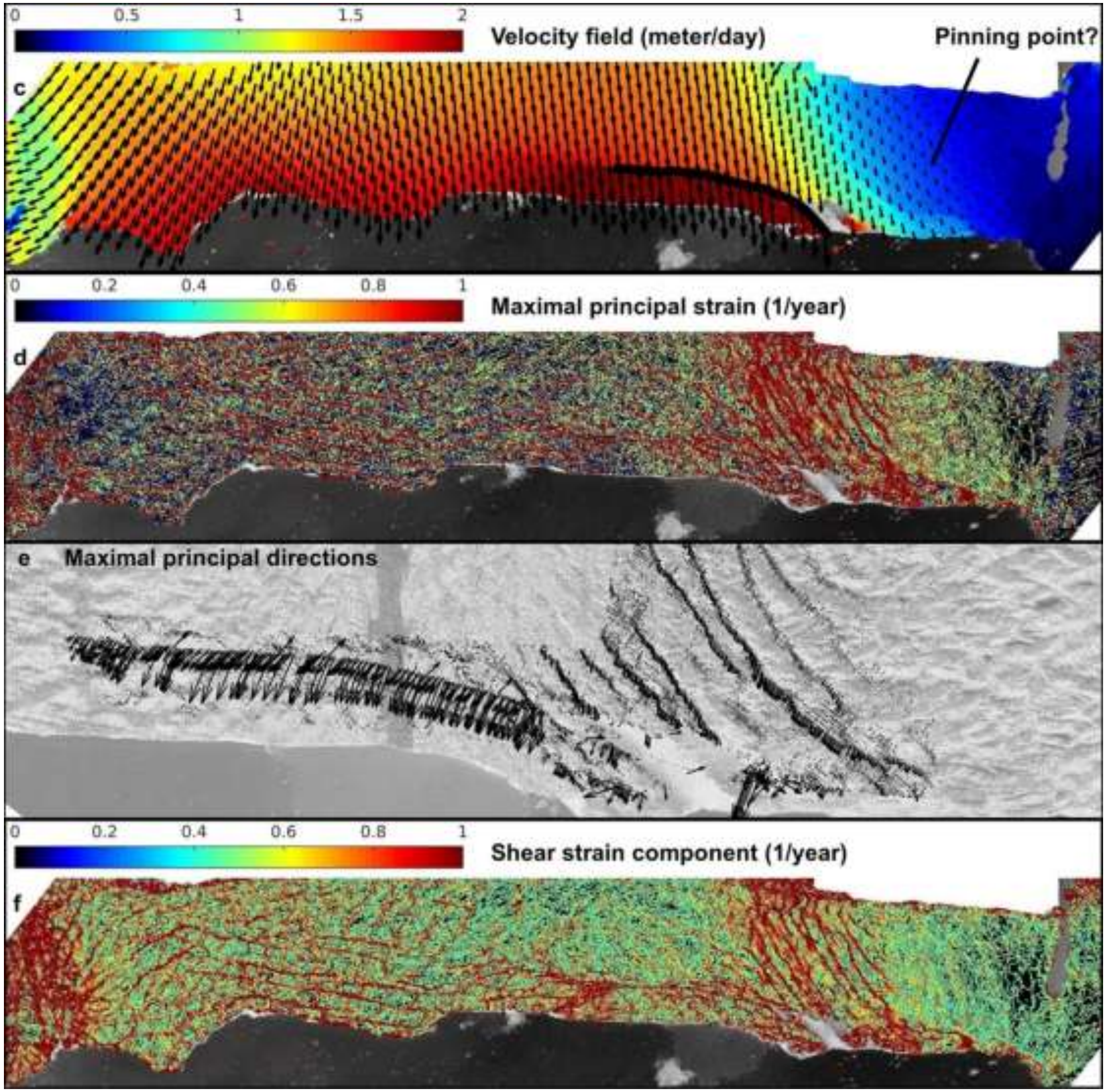
Results – Initiating calving events

Mai 2015 **July 2015**



3 - 4 events in < 1 month ~ 20% of the yearly amount of calving

Results – Derived analysis



Velocity field

Maximal principal strain

Maximal principal directions

Shear strain component

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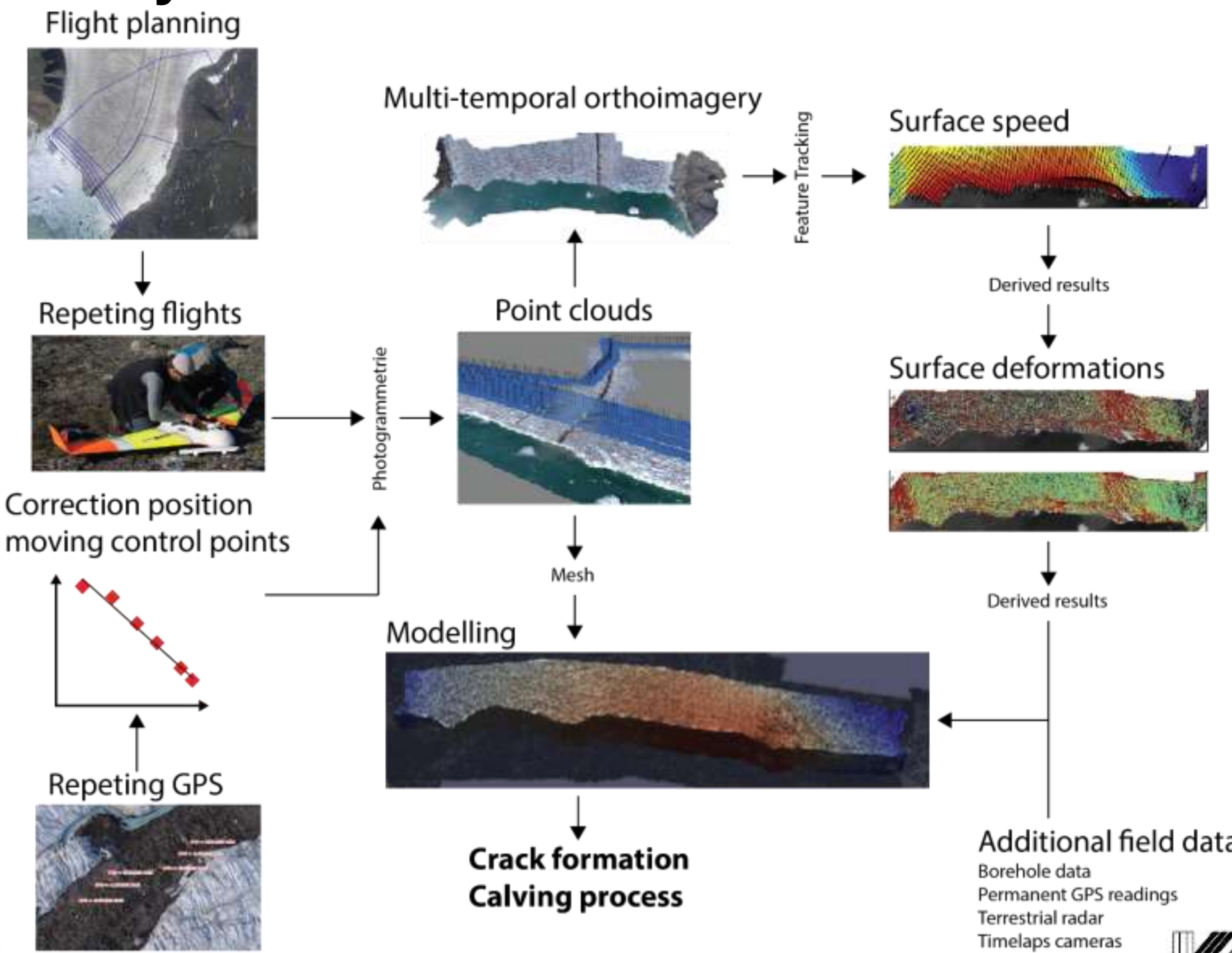
Summary – Workflow and Results



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Summary – Homemade UAV

- **Conception and assembling:**
  - \+ Very economic but durable standard RC components
  - \+ Free configuration and extension
  - \+ Full access to flight parameters
  - \+ Access to all log parameters and -analysis
  - \- Massive underestimation of the complexity and needed effort
- **Application:**
  - \+ Very efficient behaviour during the flight
  - \+ Well and efficient to fix
  - \+ Complex missions and large distances
  - \- Demanding pre-flight-procedure and launching
  - \- Large landing space

Thank you for your attention

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