

IMPROVEMENTS AND LIMITS IN THE USE OF AN INFRARED CAMERA FOR PAVEMENT THERMAL MAPPING

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Ressources, territoires et habitats
Énergie et climat
Prévention des risques
Développement durable
Infrastructures, transports et mer

Présent
pour
l'avenir



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Summary

- 1- Objectives
- 2- Implementation of infrared camera
- 3- Results - Winter risk estimations
- 4- Conclusion - Perspectives



1- Objectives

Context:

- Instrument on a vehicle to establish road susceptibility to ice
- Measurements on one lane at a time \Rightarrow tests too long
- Measurements on a small spot (*radiometer FOV 20°*)
- No appreciation of road radiative environment

Objectives:

- Implement an IR camera on a vehicle,
- Analyze several lanes simultaneously,
- Compare results from the IR camera and a radiometer,
- Improve winter risk definition

2- Implementation of IR camera

Radiometer PRT5 (BARNES Pyrometer) (reference):

Detector type: bolometer

Spectral band: 9.5 - 11.5 μm

Temperature range: -40°C to $+70^{\circ}\text{C}$

Sensitivity: 0.1°C below 0°C , 0.05°C above 0°C

Accuracy: $\pm 0.5^{\circ}\text{C}$

FOV: 20°

Response time: 50 ms

NET : 0.005 for a time response of 50 ms on a body at 25°C



IR Camera FLIR S65 :

Detector type: uncooled microbolometer 320x240 matrix IRFPA

Spectral band: 7.5 - 13 μm

Temperature range: -40°C to $+120^{\circ}\text{C}$

Sensitivity: 0.08°C

Accuracy : $\pm 2\%$ of the measurement

FOV: $24^{\circ}\times 18^{\circ}$ (HxV) (35 mm focal lens)

IFOV : 1,3 mrad



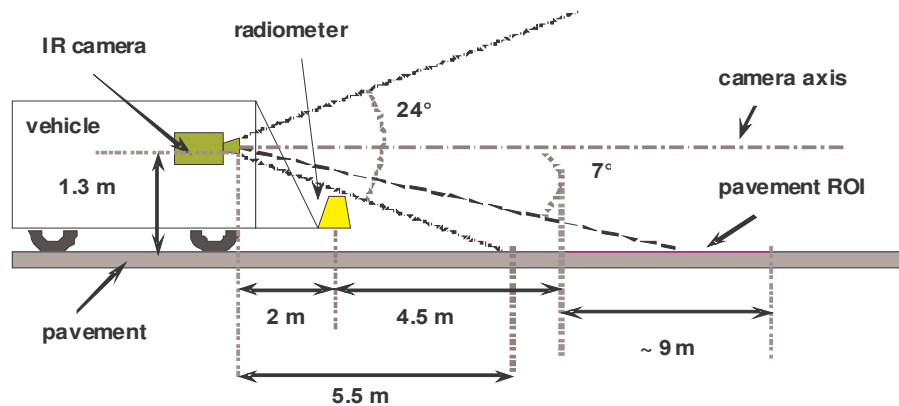
atmospheric probes

radiometer

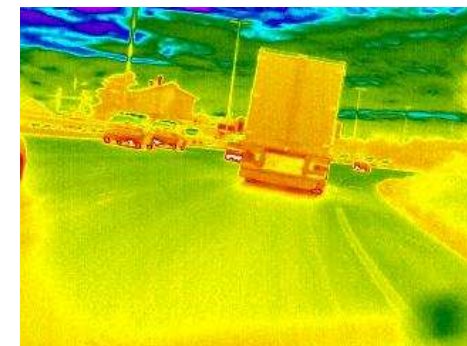
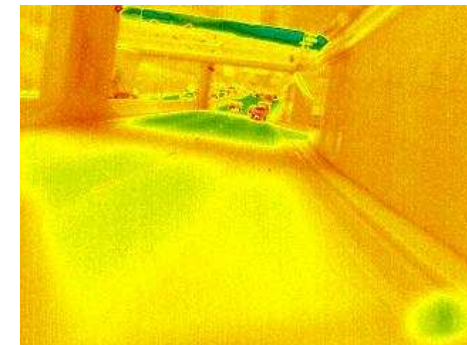
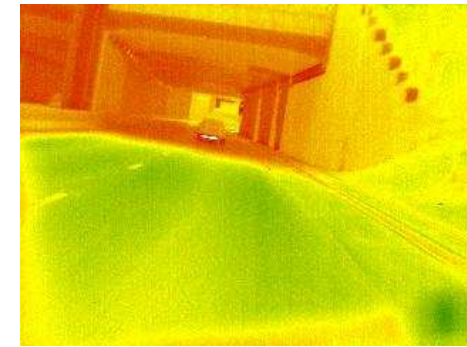


distance trigger

Thermal mapping vehicle



Scheme of the camera installed on the vehicle



IR images ($-50^{\circ}\text{C} < T < +10^{\circ}\text{C}$)

Itinerary characteristics

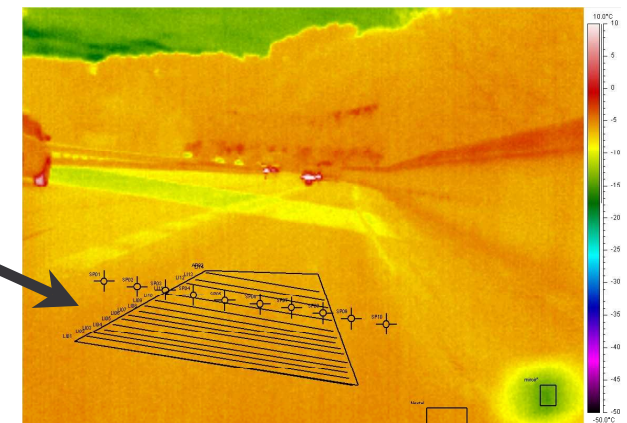
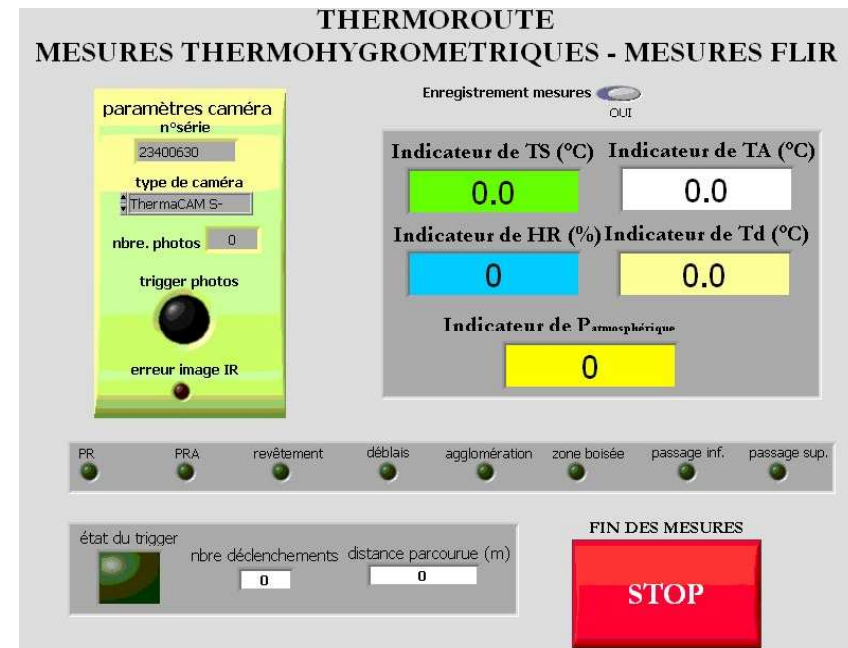
- 30 km long
- local & main roads, highways

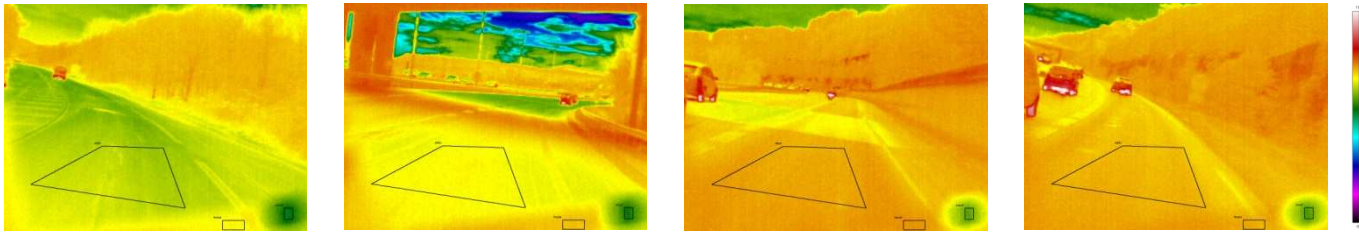
Data acquisition

- atmospheric parameters every 3 m
- thermal images every 12 m
(native format)
- maximum speed 70 km/h \approx 44 mph
- LabVIEW® interface

Choice of an appropriate data analysis areas

- (not directly affected by traffic)*
- for emissivity correction
- for evaluation of transverse winter risk





IR images ($-50^{\circ}\text{C} < T < +10^{\circ}\text{C}$)

Use of several regions of interest (ROI):

- ROI dedicated to road pavement
- Introduction of a "mirror" for environment correction ($\epsilon=0.063$)
- Introduction of Nextel Velvet 811-21 as an emissivity reference ($\epsilon=0.97$)

Distance offset between data from the radiometer and data from the IR camera (offset ≈ 12 m)

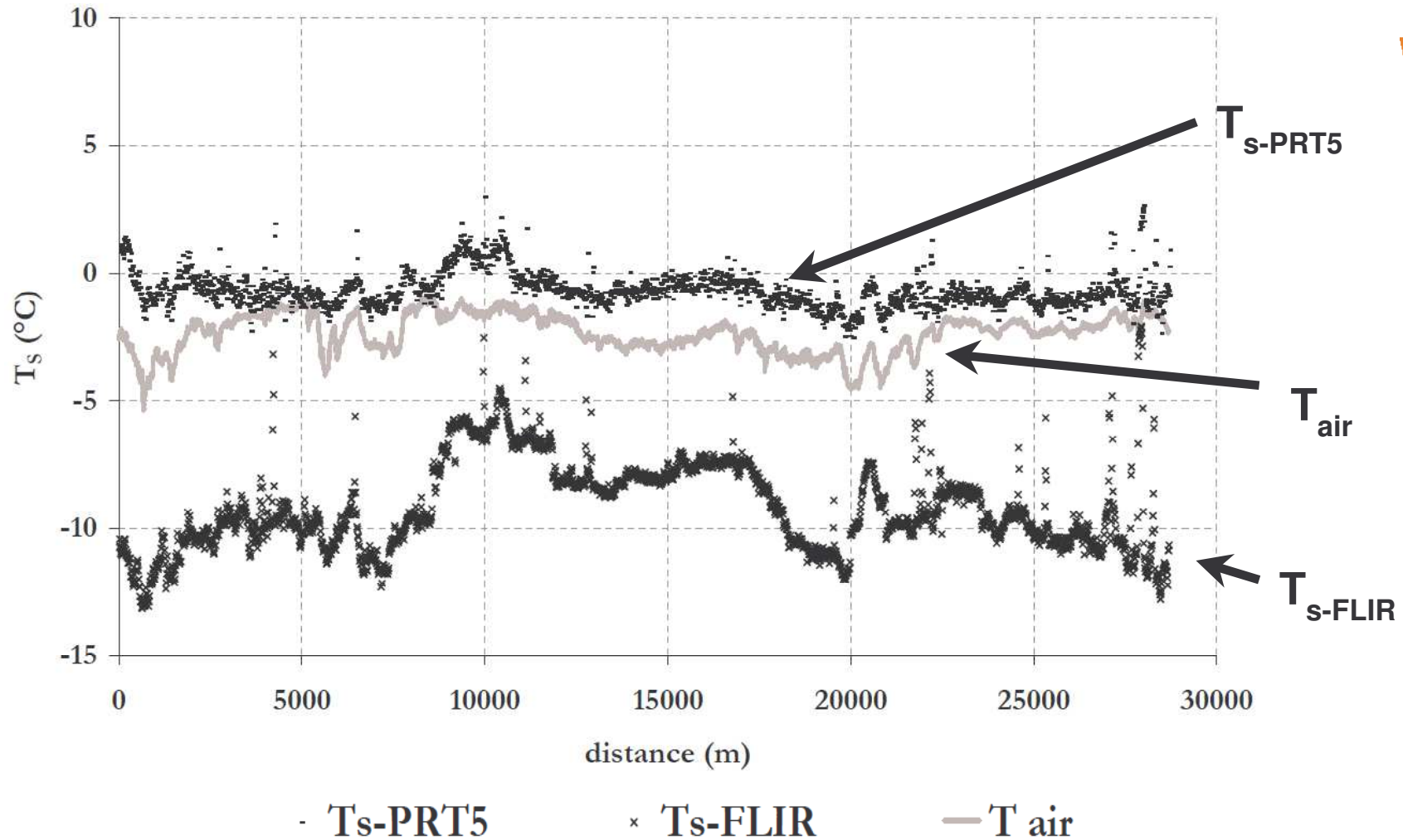
Thermal images triggered in "snapshot" mode every 12 m

- integration time of a few ms \Rightarrow slight blur in the images over 2 pixels
- compensation with ROI size \gg blur size

Atmospheric parameters (T_{air} , relative humidity) as inputs in the IR camera

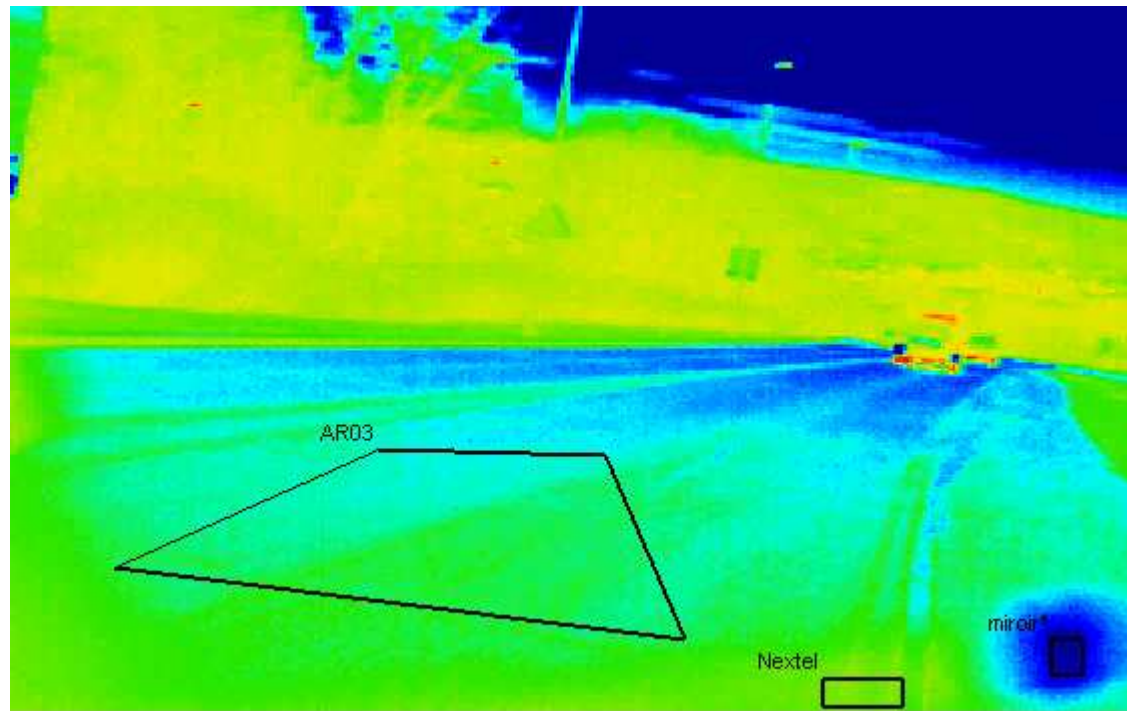
3- Results. Winter risk estimations

3.1. Temperature and radiative corrections



Results before any correction

Thermal images sequence of the Itinerary



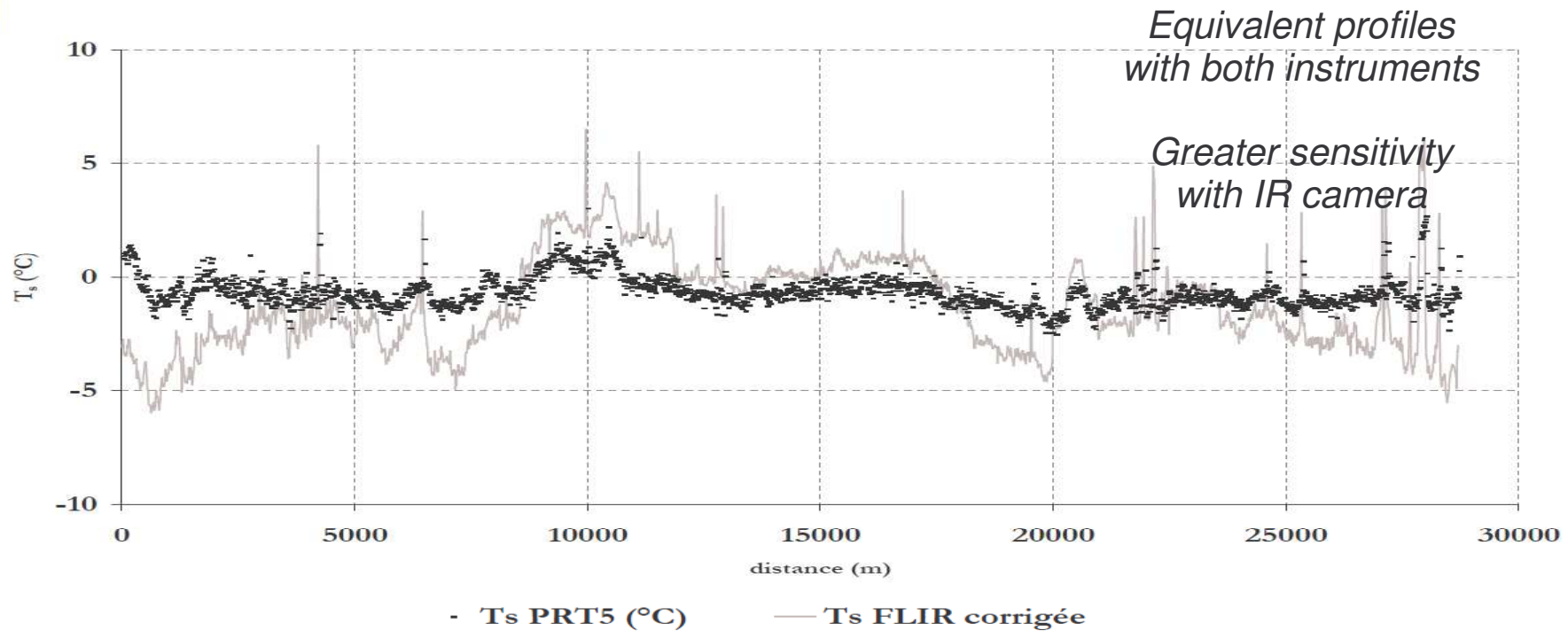
Radiometric balance

$$L_{measured} = \tau_{atmosphere} \cdot \epsilon_{pavement} \cdot L_{pavement} + \tau_{atmosphere} \cdot (1 - \epsilon_{pavement}) \cdot L_{environment} + (1 - \tau_{atmosphere}) \cdot L_{atmosphere}$$

Radiometric corrections

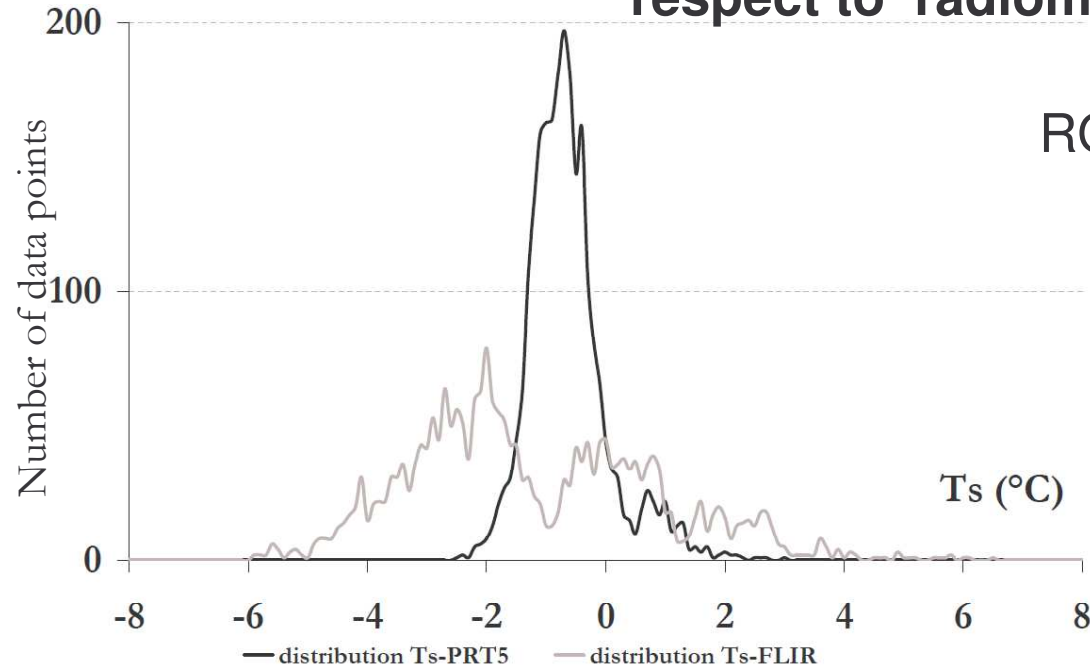
- low distance and clear atmosphere: $\tau_{atmosphere} \sim 1$
 - no specularity: Stefan law $L = \sigma T^4$
 - emissivity correction over the pavement ROIs
- ⇒ emissivity distribution over pavement ROI

$$T_{measured}^4 = \epsilon_{pavement} \cdot T_{pavement}^4 + (1 - \epsilon_{pavement}) \cdot T_{environment}^4$$

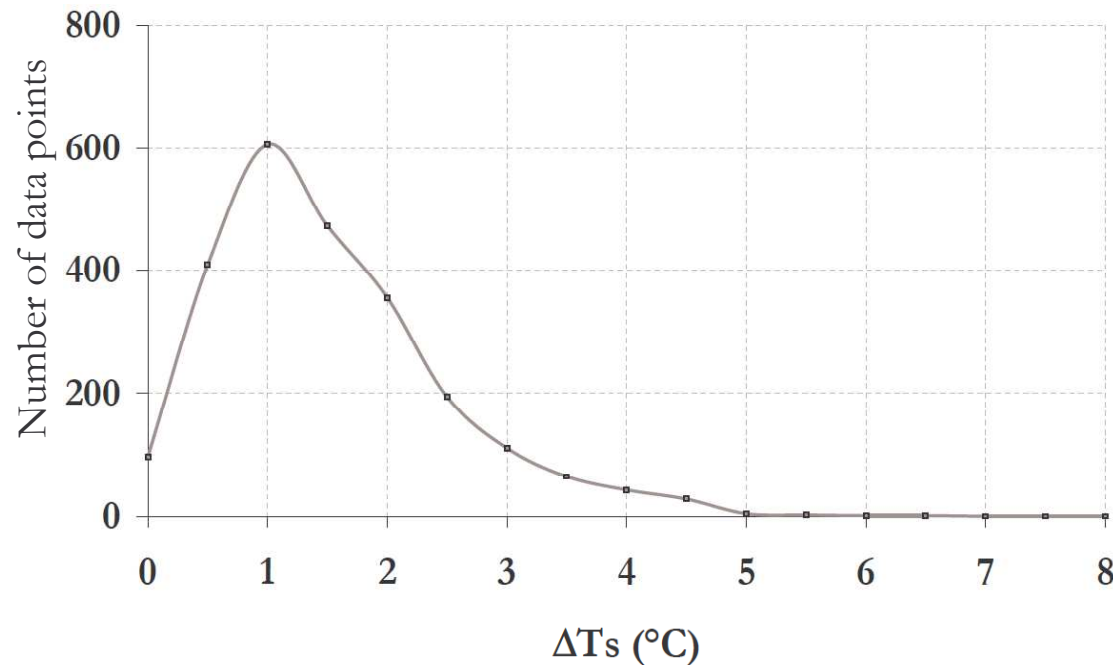


Results after radiometric corrections

Data dispersion in pavement ROI from the IR camera with respect to radiometer



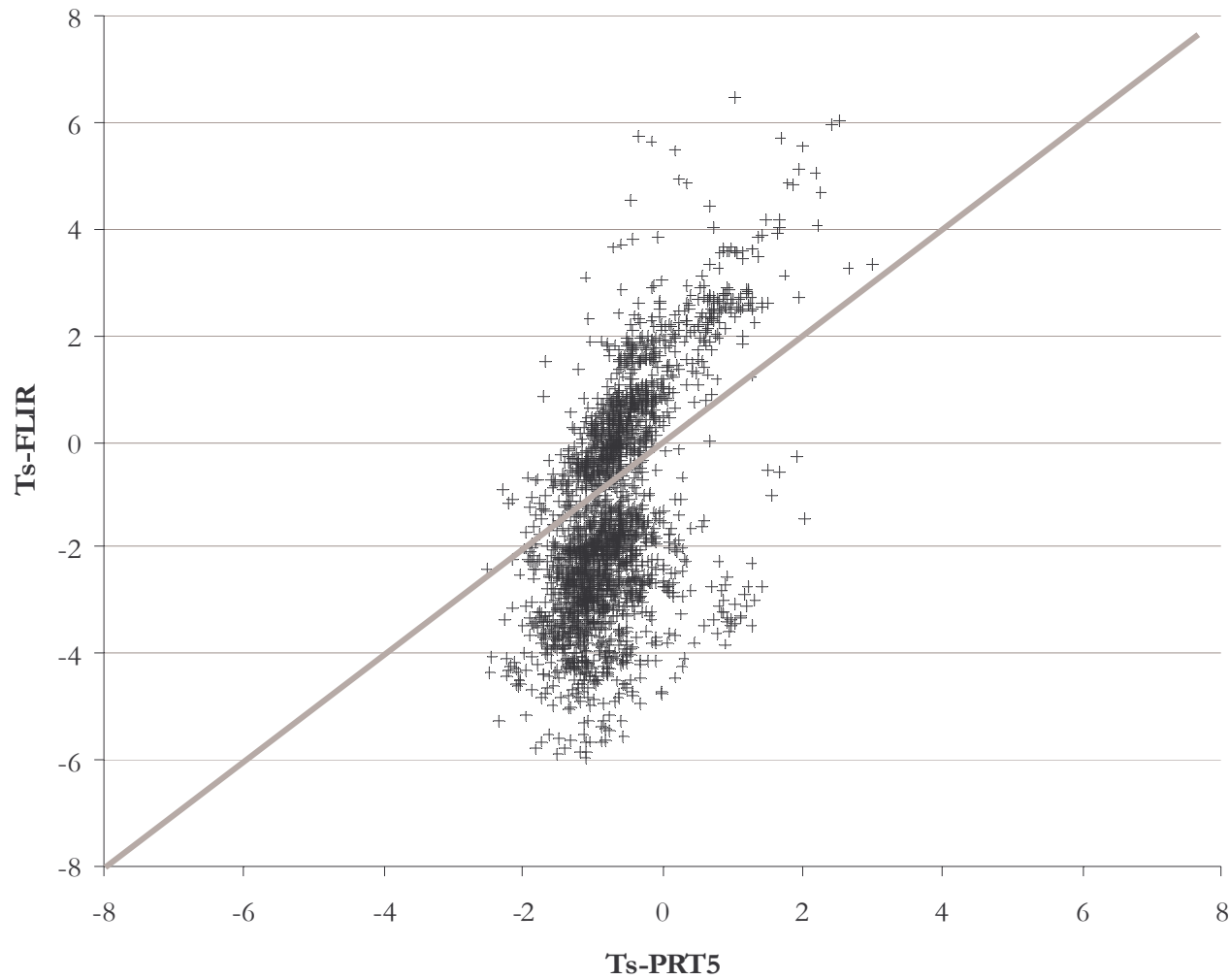
ROI IR camera more extended than the one of radiometer
⇒ greater temperature variations

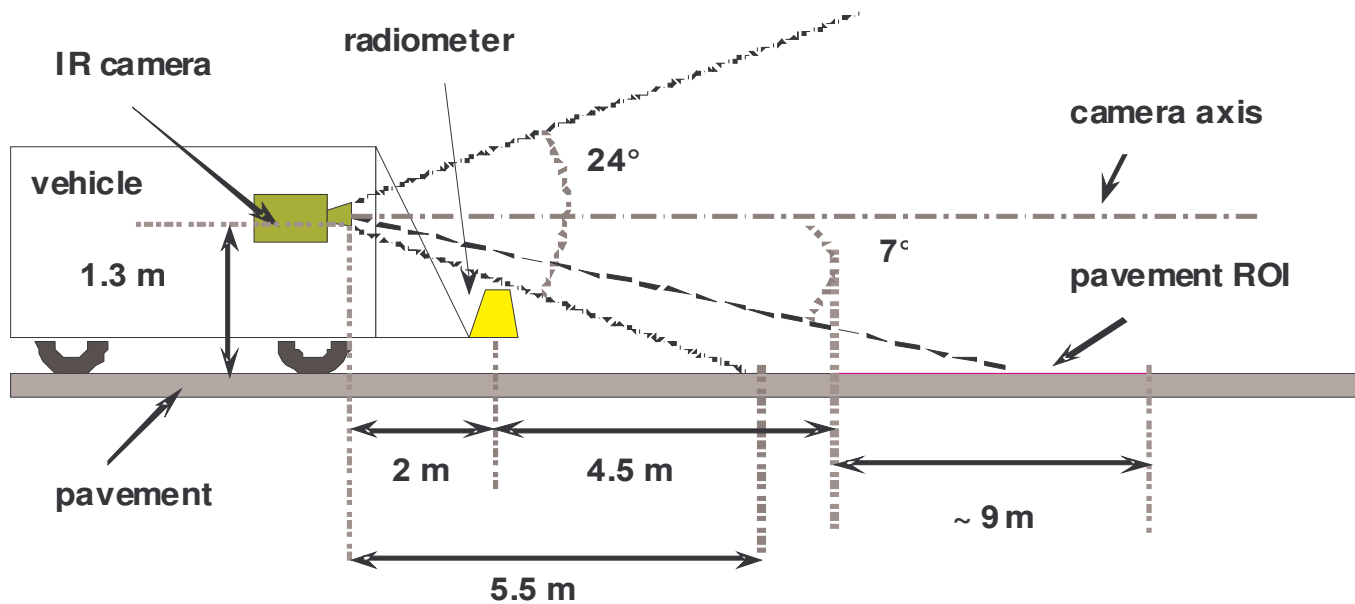


Absolute values of temperature differences between the two instruments

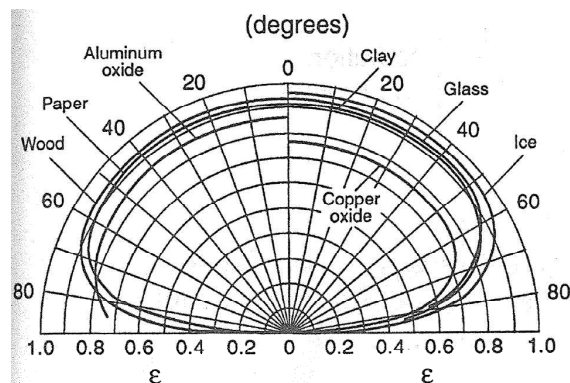


correlation between T_{s-FLIR} and T_{s-PRT5}





emissivity correction to be improved over the pavement ROI
 \Rightarrow emissivity distribution over pavement ROI



Gaussorgues, 1981

Observation angle:

$$\alpha_{\text{average}} \approx 7^\circ$$

$$\alpha_{\text{min}} \approx 4^\circ$$

$$\alpha_{\text{max}} \approx 11^\circ$$

Small angle reduction or increase = large emissivity change

3.2. Winter risk index.

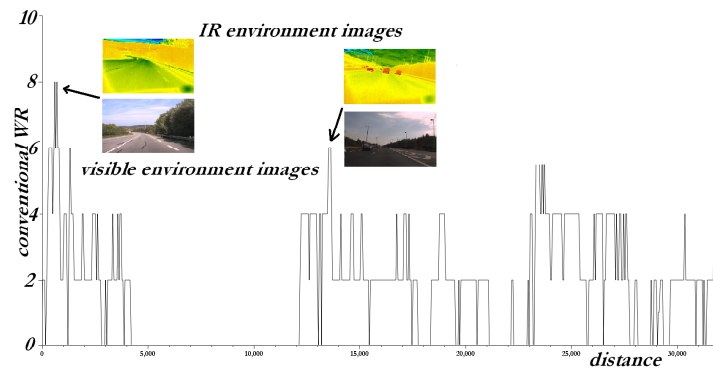
Consistency with seasons and infrastructure

Approach based on a moving average

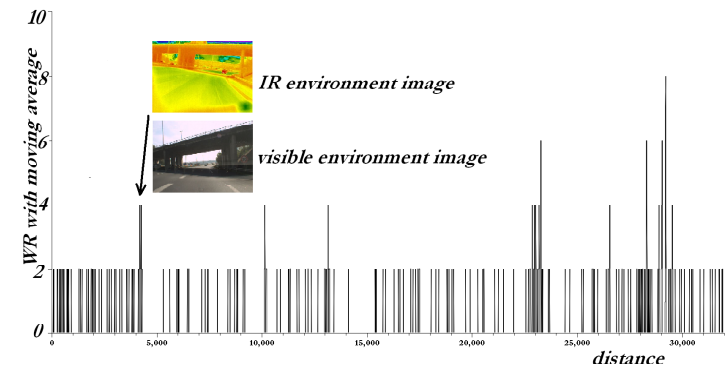
$$WR = 2 \cdot WR(T_s) + WR(T_d),$$

with $WR(T_s) = 0$ if $0^\circ\text{C} \leq T_{s,\text{moving average}} - T_s < 0.5^\circ\text{C}$; 1 if $0.5^\circ\text{C} \leq T_{s,\text{moving average}} - T_s < 1^\circ\text{C}$; ...

and $WR(T_d) = 0$ if $0^\circ\text{C} \leq T_{d,\text{moving average}} - T_d < 0.5^\circ\text{C}$; 1 if $0.5^\circ\text{C} \leq T_{d,\text{moving average}} - T_d < 1^\circ\text{C}$; ...



2009-01-31
former conventional WR as a function
of distance (in m)

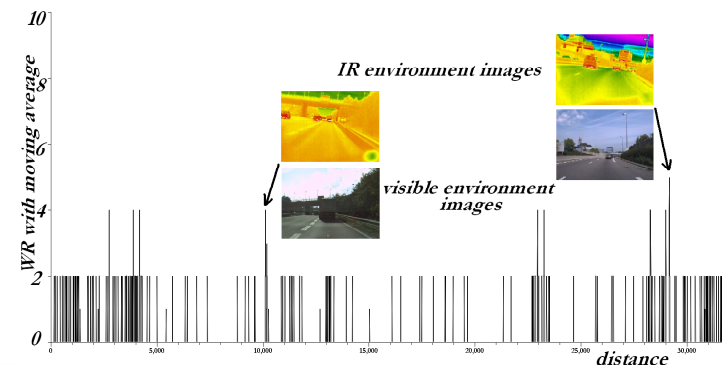


2009-01-31
moving average WR as a function of
distance (in m)

greater consistency with the infrastructure ...

... and with seasons

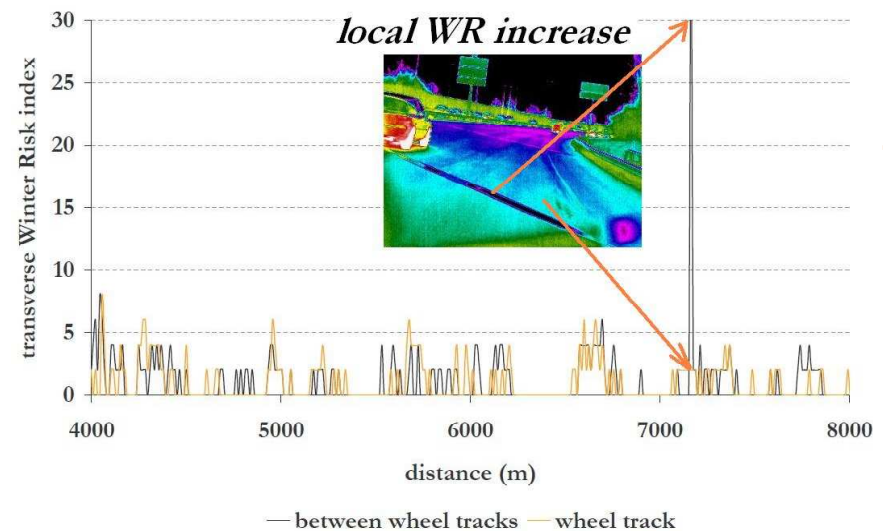
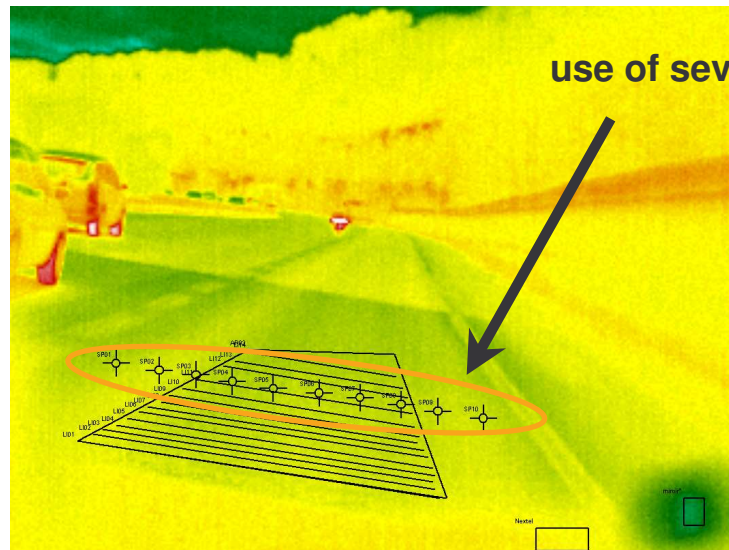
2009-08-19
moving average WR as a function of
distance (in m)



3.3. Evaluation of a transverse winter risk index

Continuous rolling of vehicles wheels \Rightarrow thermal specificity of wheel tracks

Additional investigation on the existence of a transverse winter risk (preferential wearing of the asphalt concrete in this part of pavement surface)



No significant detected difference except for specific spots
Analysis very local \Rightarrow disappearance of WR in the wheel track with respect to the situation between the wheel tracks compensated by the occurrence of new WR elsewhere

4- Conclusion. Perspectives

Efficiency of the implementation of an IR camera for thermal mapping

Radiometric corrections :

- **emissivity corrections / grazing angle**
- **signal weakening / distance camera pavement**
- **detailed analysis of measured differences / radiometer**
(*nature structures, radiative environment*)

Improvements already implemented

- **better IR camera position (several lanes monitored)**
- **increased data acquisition frequency**



Thanks for your attention

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