Imprint and Version

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1 Overview

1.1 Overview

eCognition 9.0 is a comprehensive image analysis platform for multi-dimensional image analysis. It contains all the client and server software needed to extract information from any digital image in a fully-automated or semi-automated way.

1.2 About eCognition 9.0

eCognition 9.0 is a major functional update to eCognition 8.9 and includes a significant number of new functionality and bug fixes. Trimble recommends customers review these release notes to plan any update. If you have questions please contact us via the web form on www.eCognition.com/support.

Figure 1.1. eCognition Products
1.3 eCognition 9.0 Highlights

Native Vector Handling

The new release introduces Native Vector Handling for more efficient GIS data management inside eCognition. This includes common GIS functions to visualize, inspect, create, manipulate, update and export vector data. Furthermore, GIS layers and image objects can be synchronized dynamically.

![Native Vector Handling Diagram](image)

Figure 1.2. Native Vector Handling

The new spatial and contextual GIS data modeling capabilities can be performed inside eCognition, without the requirement for a link or bridge to GIS. This improved integration of GIS techniques into remote sensing workflows is further bridging the gap between the two domains.

Template Matching

eCognition 9.0 extends the existing knowledge-based and supervised classification methods with computer vision based object detection. The new Template Editor Window allows users to easily collect samples to define the search template that is applied over the imagery data. Additionally, a template matching algorithm is available to create a correlation coefficient layer used to detect objects. This provides additional value for remote sensing experts by improving classification results and extending eCognition to new fields of use inside and outside the remote sensing domain.

Point Cloud Viewer

To manage the complexities associated with creating information from LiDAR or dense image matching point clouds, eCognition 9.0 introduces a 3D point cloud viewer. Users can visualize points by classification, intensity, RGB values for an easier and better data and result assessment.
Figure 1.3. Template Matching

Figure 1.4. Point Cloud Viewer
This can significantly increase the productivity of creating rule sets as well as improving the classification quality. This opens new application fields for instance in the mobile mapping domain.

**JPEG2000 Support**

eCognition 9.0 allows loading of compressed JPEG2000 image data with geocoding and resolution information which offers faster turnaround times for projects using the latest set of earth observation sensors like Pleiades satellites.

By direct access to this latest compression technology, no additional conversion operation is necessary.

![Figure 1.5. Support of JPEG2000 Image Data](image)

**Trusted Storage**

The license handling based on license files is replaced in eCognition 9.0 with Trusted Storage. The new approach provides a secure environment for online license management. Users can easily activate and re-host eCognition licenses online which reduces bottlenecks due to necessary communication loops with the license vendor.

![Figure 1.6. eCognition Licensing based on Trusted Storage](image)
1.4 Key Features

- Available rule-based eCognition clients for application developers and end users:
  - eCognition Developer
  - eCognition Architect
- eCognition Server: A scalable, server-based batch processing environment for multidimensional analysis.

Figure 1.7. Key Features - eCognition multi-dimensional image analysis software
## 2 New Features, Bug Fixes and Limitations

### 2.1 New Features

See table 2.1 on this page, *New Features in eCognition 9.0*.

**Table 2.1. New Features in eCognition 9.0**  

<table>
<thead>
<tr>
<th>Story</th>
<th>Feature</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Native Vector</td>
<td>Improved 2D visualization: vector layer support</td>
<td>Visualize vector data keeping the original geometry: display vectors without snapping vertices/nodes to pixel corners and without rasterization of lines and polygons</td>
</tr>
<tr>
<td>Handling</td>
<td></td>
<td>-------------------------------------------------------------------------------------------------------</td>
</tr>
<tr>
<td>Native Vector</td>
<td>New Dialog: ‘Edit Vector Layer Mixing’</td>
<td>Control how vector data is displayed: set layer order, outline color, fill color, transparency and auto update of vector layers</td>
</tr>
<tr>
<td>Handling</td>
<td></td>
<td>-------------------------------------------------------------------------------------------------------</td>
</tr>
<tr>
<td>Native Vector</td>
<td>New Process Domain: ‘vectors’</td>
<td>Addressing the scope of an algorithm to vector layer(s) or specific vector objects (defined by vector features)</td>
</tr>
<tr>
<td>Handling</td>
<td></td>
<td>-------------------------------------------------------------------------------------------------------</td>
</tr>
<tr>
<td>Native Vector</td>
<td>Introduce temporary vector layer concept</td>
<td>Create temporary vector layers to enable efficient data access to focus the analysis on areas of interest or to extract a copy for processing</td>
</tr>
<tr>
<td>Handling</td>
<td></td>
<td>-------------------------------------------------------------------------------------------------------</td>
</tr>
<tr>
<td>Native Vector</td>
<td>Improved Algorithm: ‘create temporary thematic vector layer’</td>
<td>Create a copy (temporary vector layer) of an existing vector layer for further vector analysis steps</td>
</tr>
<tr>
<td>Handling</td>
<td></td>
<td>-------------------------------------------------------------------------------------------------------</td>
</tr>
<tr>
<td>Native Vector</td>
<td>New Algorithm: ‘convert image objects to vector objects’</td>
<td>Convert image objects to polygon, line or point vector objects (temporary vector layer) for further vector analysis</td>
</tr>
<tr>
<td>Handling</td>
<td></td>
<td>-------------------------------------------------------------------------------------------------------</td>
</tr>
<tr>
<td>Native Vector</td>
<td>New Algorithm: ‘vector boolean operation’</td>
<td>Perform an overlay analysis on specified operations: union, intersection, subtract or difference</td>
</tr>
<tr>
<td>Handling</td>
<td></td>
<td>-------------------------------------------------------------------------------------------------------</td>
</tr>
<tr>
<td>Story</td>
<td>Feature</td>
<td>Description</td>
</tr>
<tr>
<td>-------</td>
<td>---------</td>
<td>-------------</td>
</tr>
<tr>
<td>Native Vector Handling</td>
<td>New Algorithm: ‘vector simplification’</td>
<td>Simplify the shape of selected vector layers using the Douglas-Peucker algorithm</td>
</tr>
<tr>
<td>Native Vector Handling</td>
<td>New Algorithm: ‘vector smoothing’</td>
<td>Smooth straight edges and angular corners of lines or polygons based on Polynomial or Cubic Bezier interpolations</td>
</tr>
<tr>
<td>Native Vector Handling</td>
<td>New Algorithm: ‘vector orthogonalization’</td>
<td>Generalize polygons into rectilinear (orthogonal) polygons at specified granularity</td>
</tr>
<tr>
<td>Native Vector Handling</td>
<td>New Algorithm: ‘vector integration’</td>
<td>Integrate polygon layers with each other to create a new layer with identical or coincident lines/vertices that are within a certain distance of one another</td>
</tr>
<tr>
<td>Native Vector Handling</td>
<td>New Algorithm: ‘vector dissolve’</td>
<td>Merge vector objects based on specified attributes</td>
</tr>
<tr>
<td>Native Vector Handling</td>
<td>New Algorithm: ‘vector remove intersections’</td>
<td>Remove intersections in vector layers (polygons)</td>
</tr>
<tr>
<td>Native Vector Handling</td>
<td>New Algorithm: ‘delete vector objects’</td>
<td>Delete vector objects from vector layers, defined in the vector domain</td>
</tr>
<tr>
<td>Native Vector Handling</td>
<td>New Algorithm: ‘modify thematic attribute column’</td>
<td>Update, add, remove or rename attribute columns of thematic layers</td>
</tr>
<tr>
<td>Native Vector Handling</td>
<td>Improved Algorithm: ‘write thematic attributes’</td>
<td>Generate an attribute column entry from an image object feature to update vector layers</td>
</tr>
<tr>
<td>Native Vector Handling</td>
<td>Improved Image Object Information Window: vector feature support</td>
<td>Display vector feature values in the Image Object Information Window, i.e. vector object attributes</td>
</tr>
<tr>
<td>Native Vector Handling</td>
<td>New Object Feature: ‘Vector object attribute’</td>
<td>Shows attribute table values of selected vector objects</td>
</tr>
<tr>
<td>Native Vector Handling</td>
<td>New Object Feature: ‘Minimum overlap [%] with thematic polygons’</td>
<td>Computes the minimum value of the overlap between an image object and a vector object in percent</td>
</tr>
<tr>
<td>Native Vector Handling</td>
<td>New Object Feature: ‘Maximum overlap [%] with thematic polygons’</td>
<td>Computes the maximum value of the overlap between an image object and a vector object in percent</td>
</tr>
<tr>
<td>Native Vector Handling</td>
<td>New Scene Feature: ‘all existing temporary thematic layers’</td>
<td>Shows a dynamic list of existing temporary thematic layers in the project to initialize layer arrays</td>
</tr>
<tr>
<td>Native Vector Handling</td>
<td>Improved FileGDB driver</td>
<td>Loading and exporting point and line feature classes from/to FileGDBs</td>
</tr>
</tbody>
</table>

*Continues…*
### New Features, Bug Fixes and Limitations

**Story** | **Feature** | **Description**
--- | --- | ---
Native Vector Handling | Improved Algorithm: ‘export vector layer’ | Export vector layer into an existing FileGDB
Native Vector Handling | Improved Algorithm: ‘export existing vector layer’ | Export a temporary thematic vector layer to a file (saving vector analysis results)
Template Matching | New Dialog: ‘Template Editor’ - Sample Selection | GUI to collect and optimize template samples
Template Matching | New Dialog: ‘Template Editor’ - Template Generation | GUI to compute templates or template groups based on collected template samples
Template Matching | New Dialog: ‘Template Editor’ - Test Templates | GUI to test templates and to collect automatically additional template samples
Template Matching | New Algorithm: ‘template matching’ | Perform a template matching procedure to create a correlation coefficient image layer for object detection
Point Cloud Viewer | Improved Viewer: 3D point cloud rendering support | Visualize point clouds in 3D coming from LiDAR or dense image matching
Point Cloud Viewer | Improved Viewer: 3D mouse navigation | Mouse navigation to interact with the 3D point cloud viewer: left mouse button or scroll wheel = Zooming, right mouse button = rotating, both mouse buttons = panning
Point Cloud Viewer | New Menu Button: ‘Point Cloud View or Image View’ | Toggle between 3D visualization mode and 2D image view
Point Cloud Viewer | New Dialog: ‘Point Cloud View Settings’ | GUI to define 3D point cloud setting: input layer, level of detail, point size and different rendering modes (intensity, classification, RGB)
JPEG2000 | New JPEG2000 driver | Support of compressed JPEG2000 images (*.jp2) with geocoding and resolution information
Trusted Storage | New License Management Tool | GUI for license handling based on Trusted Storage: online license Activation and online license Return
Usability | Improved Algorithm: ‘classifier’ - importance values support | Option to query and store importance values and corresponding features from a trained CART classifier into arrays
Usability | Improved Algorithm: ‘classifier’ - feature space array support | Use features from a feature array instead of selected features to train a classifier

*Continues…*
New Features, Bug Fixes and Limitations

**Story Feature Description**

**Usability Improved Algorithm:** ‘classifier’ export variable support

Export variable support (i.e. `{:W orkspc.OutputRoot}`) for query export paths (plot, parameter)

**Usability Improved Algorithm:** ‘LiDAR file converter’

Enabled Process Domain to execute algorithm on defined maps

**Usability New Algorithm:** ‘calculate random number’

Calculate a random value and store it in a variable

**Usability New Algorithm:** ‘create/update class’

Creates object classes based on features and allows to change class names, class color, class comments and class scope

**Usability Improved Feature:** ‘distance to line’

Scene variable support for input parameters of “distance to line” feature

**Usability Improved Algorithm:** ‘set custom view settings’

Extension to define thematic layer mixing (layer order, outline color, fill color, and transparency)

**Usability New MX8 Predefined Import Routine**

“MX8 - All Camera View - AVI+LAS All” create projects where all available Camera perspectives are stored in separate maps

<table>
<thead>
<tr>
<th>Story</th>
<th>Feature</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Usability</td>
<td>Improved Algorithm: ‘classifier’ - export variable support</td>
<td>Export variable support (i.e. <code>{:Workspc.OutputRoot}</code>) for query export paths (plot, parameter)</td>
</tr>
<tr>
<td>Usability</td>
<td>Improved Algorithm: ‘LiDAR file converter’</td>
<td>Enabled Process Domain to execute algorithm on defined maps</td>
</tr>
<tr>
<td>Usability</td>
<td>New Algorithm: ‘calculate random number’</td>
<td>Calculate a random value and store it in a variable</td>
</tr>
<tr>
<td>Usability</td>
<td>New Algorithm: ‘create/update class’</td>
<td>Creates object classes based on features and allows to change class names, class color, class comments and class scope</td>
</tr>
<tr>
<td>Usability</td>
<td>Improved Feature: ‘distance to line’</td>
<td>Scene variable support for input parameters of “distance to line” feature</td>
</tr>
<tr>
<td>Usability</td>
<td>Improved Algorithm: ‘set custom view settings’</td>
<td>Extension to define thematic layer mixing (layer order, outline color, fill color, and transparency)</td>
</tr>
<tr>
<td>Usability</td>
<td>New MX8 Predefined Import Routine</td>
<td>“MX8 - All Camera View - AVI+LAS All” create projects where all available Camera perspectives are stored in separate maps</td>
</tr>
</tbody>
</table>

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### 2.2 Bug Fixes

See **table 2.2** on the current page, *Bug Fixes in eCognition 9.0*.

**Table 2.2. Bug Fixes in eCognition 9.0**

<table>
<thead>
<tr>
<th>Reference</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>ECOG-00115</td>
<td>eCognition GRID 64 uninstall: Au_.exe has stopped working</td>
</tr>
<tr>
<td>ECOG-00376</td>
<td>Action Library: Loading solution from outdated eCognition version pops up error message</td>
</tr>
<tr>
<td>ECOG-00563</td>
<td>GRID: license problems when installing new packages</td>
</tr>
<tr>
<td>ECOG-00853</td>
<td>Missing ‘Feature View’ button in ‘View Settings’ toolbar</td>
</tr>
<tr>
<td>ECOG-00855</td>
<td>Import Image Layer dialog: ‘File Name Filter’ do not work if ‘Search Subfolders’ is active</td>
</tr>
<tr>
<td>ECOG-00856</td>
<td>Areas in shapefiles without polygons is not segmented and classified correctly</td>
</tr>
<tr>
<td>ECOG-00881</td>
<td>Export results from *.las file does not contain projection information</td>
</tr>
</tbody>
</table>

Continues...
<table>
<thead>
<tr>
<th>Reference</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>ECOG-00892</td>
<td>Encrypted customized algorithms are not showed in Process Tree</td>
</tr>
<tr>
<td>ECOG-00916</td>
<td>Shapefile rasterization creates holes between polygons</td>
</tr>
<tr>
<td>ECOG-00918</td>
<td>Synchronize map algorithm: rounding problems when resolution is increased</td>
</tr>
<tr>
<td>ECOG-00920</td>
<td>Wrong calculation of Quantile 100 feature</td>
</tr>
<tr>
<td>ECOG-00957</td>
<td>Export point cloud algorithm: shift when exporting from las 1.1</td>
</tr>
<tr>
<td>ECOG-00962</td>
<td>Crash when zooming based on data in different resolutions</td>
</tr>
<tr>
<td>ECOG-00963</td>
<td>Zoom factor display does not update</td>
</tr>
<tr>
<td>ECOG-00980</td>
<td>Crash when using 'transfer layer' algorithm with different resoluted maps</td>
</tr>
<tr>
<td>ECOG-00986</td>
<td>Threshold condition’ dialog: using feature as threshold not allowed when using other operator than “=”</td>
</tr>
<tr>
<td>ECOG-00987</td>
<td>Slow calculation of quantile object features</td>
</tr>
<tr>
<td>ECOG-00993</td>
<td>Layer arithmetics algorithm: rounding issues when using large numbers in parameters</td>
</tr>
<tr>
<td>ECOG-01016</td>
<td>Stripes in display and classification when loading frames or slices</td>
</tr>
<tr>
<td>ECOG-01042</td>
<td>Crash when loading very large LAS v1.2 files (&gt;32 GB)</td>
</tr>
<tr>
<td>ECOG-01126</td>
<td>Shapefile: “Red”, “Green”, “Blue” attribute columns are not supported</td>
</tr>
<tr>
<td>ECOG-01152</td>
<td>Assign class by thematic layer algorithm do not support feature variables as thematic layer attribute</td>
</tr>
</tbody>
</table>

### 2.3 Known Issues and Limitations

In eCognition 9.0 it is not possible to create and use 3D raster stacks based on point cloud data, because the Z resolution of LAS files is not supported by the LAS driver anymore.

The new Trusted Storage based license system does not support license borrowing, so that the eCognition License Borrowing functionality is removed in eCognition 9.0. Customers can use local license activation instead.

### 2.4 Errata

None.
Acknowledgments

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python/tests/test_doctests.py

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src/Version.rc

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src/gt_wkt_srs.cpp

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