

CONTACT | DIRECTIONS





FRAUNHOFER INSTITUTE FOR
PHYSICAL MEASUREMENT TECHNIQUES IPM

NOVEMBER 14-15, 2018

MoLaS Technology Workshop 2018

Key Technology Drivers in Mobile Laser Scanning

Registration

Registration is possible starting March 1, 2018. Please register online: www.molas-workshop.org

Participation fees

- »Early Bird« registration until Sept.16, 2018: 200 EUR
- Participants: 250 EUR
- Students: 150 EUR (valid student card required)
 Payment upon invoice (for further details see website).

Accommodation

We have reserved a limited amount of single rooms for workshop participants from November 14 to 15, 2018.

- Hotel Stadt Freiburg | www.hotel-stadt-freiburg.de
 Rooms at 90 EUR per person per night (incl. breakfast)
- Hampton by Hilton Freiburg | www.hiltonhotels.de/ deutschland/hampton-by-hilton-freiburg
 Rooms at 99 EUR per person per night (incl. breakfast)
- Intercity Hotel Freiburg | www.intercityhotel.com
 Rooms at 80 EUR per person per night (incl. breakfast)

Please book your room directly with the hotel (keyword »MoLaS«).

Venue

Fraunhofer Institute for Physical Measurement Techniques IPM Heidenhofstraße 8, 79110 Freiburg, Germany

Chair

Alexander Reiterer, Fraunhofer IPM

Organization

Tanja Hagios
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Directions

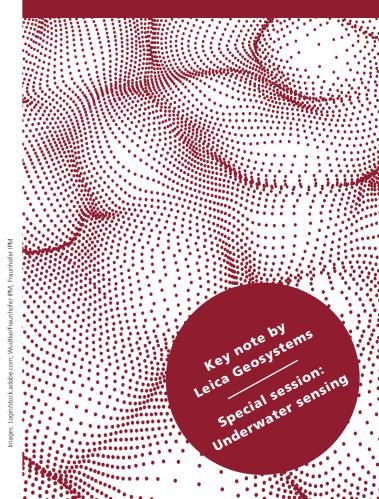
www.ipm.fraunhofer.de/directions

Registration and further information www.molas-workshop.org



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Technological trends in mobile laser scanning

Mobile laser scanning technology has made significant progress since the last MoLaS workshop in 2016. This applies to both measuring technology and data interpretation, the latter being of growing importance. The amount and quality of data generated are continuously increasing, with researchers trying to find ways to extract the most out of it. At the same time, mobile laser scanners are expanding into new fields of application such as underwater scanning.

The Third International MoLaS workshop focuses on technological trends in mobile laser scanning. Twelve internationally renowned experts will present key technology drivers and future applications in the field of 3D mapping with mobile laser scanners. Four sessions cover the entire spectrum of laser scanning technology:

- **▶** Sensors
- **▶** Calibration
- ▶ Data interpretation and visualization
- ► Applications (special focus on underwater laser scanning)

The workshop is aimed at scientists, service providers, manufacturers and users of the technology.

We are looking forward to meeting you at MoLaS 2018!

12:30 h	Registration	
13:30 h	Opening	
13:45 h	Limits to calibration: Engineers against nature's stubbornness Stefan Schwarzer, Department of Object and Shape Detection, Fraunhofer IPM, Freiburg	Sensors and calibration
14:15 h	On intensity-based stochastic models for terrestrial laser scanners Daniel Wujanz, technet GmbH, Berlin	
14:45 h	Development of laser scanning systems Antero Kukko, Finnish Geospatial Research Institute, Helsinki	
15:15 h	Coffee break / Poster session	
16:00 h	BIM modelling of an existing highway based on mobile mapping Dirk Ebersbach, Alexander Bräunlich VIA IMC GmbH, Berlin	Applications
16:30 h	Laser-based tunnel inspection Edouard Lamboray, Amberg Technologies AG, Regensdorf	
17:00 h	Laserscanning – A game-changing technology Jürgen Mayer, Leica Geosystems, Heerbrugg	Key

THURSDAY, NOVEMBER 15			
09:00 h	Fully-automated 3D-data interpretation by deep learning Katharina Wäschle, Department of Object and Shape Detection, Fraunhofer IPM, Freiburg	Data interpretation and visualization	
09:30 h	Contemporary point cloud visualization methods Christoph Müller, Faculty of Digital Media, Furtwangen University		
10:00 h	Coffee break / Poster session		
10:45 h	Optical underwater sensing – Challenges in hydrography Harald Sternberg, Chair of Engineering Geodesy, HafenCity University Hamburg		
11:15 h	Mobile mapping of partially submerged structures using structured light laser scanning Andreas Nüchter, Informatics VII – Robotics and Telematics, Julius-Maximilians- University, Würzburg	Jnderwater sensing	
11:45 h	Real-time and full-color 3D inspection of underwater structures using the SeaVision system Jakob Schwendner, Kraken Robotik GmbH, Bremen	Underwa	
12:15 h	Underwater time-of-flight laser scanning Christoph Werner, Department of Object and Shape Detection, Fraunhofer IPM, Freiburg		
12:45 h	Conclusion		
13:00 h	Workshop end		