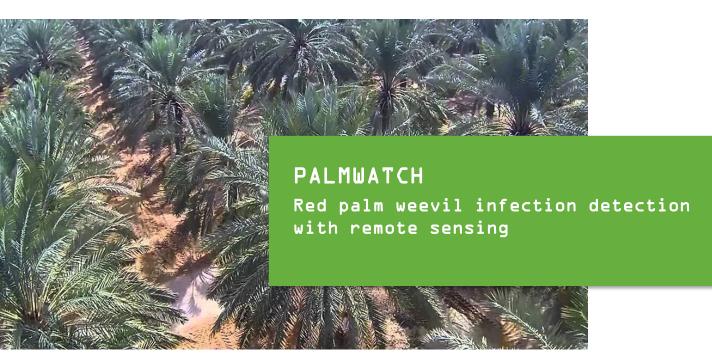
PHOENIX RESEARCH STATION











BACKGROUND

- Date palm production is an important commodity crop with a fairly large economic value:
 - US\$ 2000 per ton for prime quality.
 - Yields: 11-17 tonnes/ha.
- The **red palm weevil (RPW)** is spreading fast across palm producing countries and causes palm trees to collapse.
 - Production losses & delay.
 - Slow plantation re-establishment.
- Extremely important crop from cultural point of view: gardens and public parks
- Frequent inspection and trapping poorly implemented although efficient if palms owners and gardeners were mobilized and trained

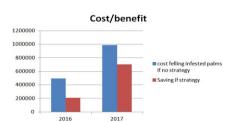
These are compelling reasons for defining a solution to the problem of red palm weevil infestation.













BACKGROUND



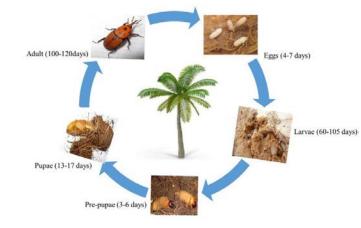
The RPW is spread by:

- Flying of adult beetles
- Trade of infested plants



The RPW causes:

- A decrease in photosynthetic rate
- A decrease in water use efficiency
- Water loss
- Yellowing
- Higher canopy temperatures
- Lower stomatal conductance
- Structural damage (e.g., chewing)

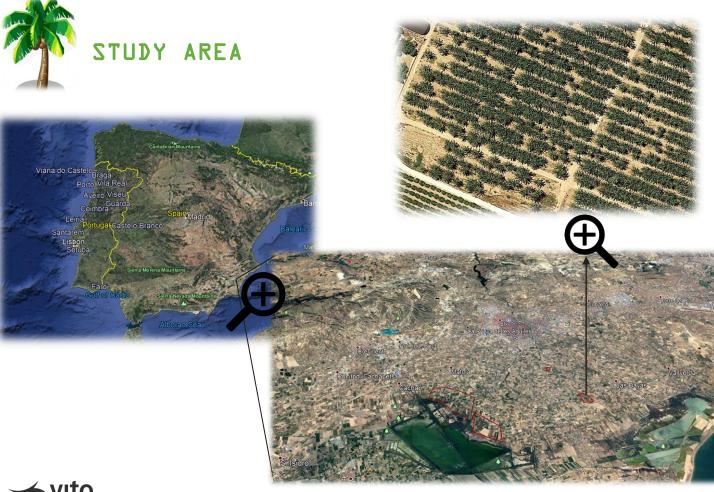
















PALMWATCH - KEY QUESTIONS





- Can we detect RPW using available RS techniques?
- At what stage will we be able to detect RPW?













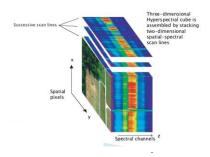


PALMWATCH - OBJECTIVES

RQ1: Can leaf biochemical changes be assessed?













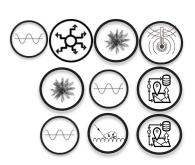
thermal



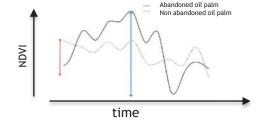


PALMWATCH - OBJECTIVES

RQ2: Can tree vitality parameters be used to detect RPW?



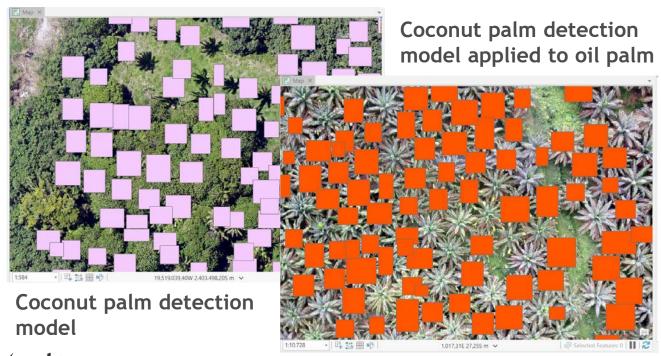
Platform	Resolution	Spatial	Spectral	Temporal
→		Very high	Very high	Low
1711		High	Very low	High
TERRA		Low	Low	Very High







LOCAL MAPPING WITH OBJECT DETECTION



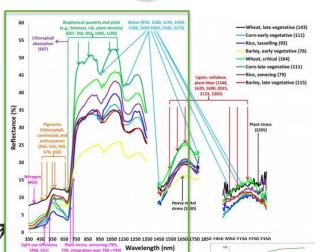




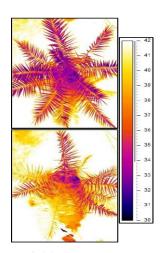
LOCAL MAPPING

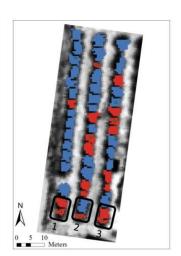
- ✓ Understanding the physiological response of the trees to RPW infection and link to RS
- ✓ Set-up an innovative RS monitoring system for a non-destructive effective local detection of RPW













REGIONAL MAPPING



Regional palm tree maps



Temporal tracking

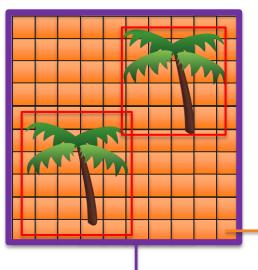
Targeted risk area mapping





CREATING GROUND TRUTH FOR S1 AND S2

Main concept: use high resolution maps to generate low resolution training data



S1/S2 pixel

- > 50% of S2 covered: palm tree pixel
- < 50% of S2 covered: background pixel

In case of palm tree pixel: density = amount of objects

Pleiades pixel

- While the Pleiades-based maps will serve a training data generation
- Additional manual lm training data will be generated for independent validation vito be





