LATEX AND BIBTEX TEMPLATE FOR ISPRS PUBLICATIONS

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ABSTRACT:

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1 INTRODUCTION

LIDAR data is being used more and more by the public sector and commercial world since the early 1990s (Maas, 2005). LIDAR data point clouds are accurate for less hilly terrain (Huising and Pereira, 1998). Geometric primitives were estimated based on histogram analysis of surface normals (Haala and Brenner, 1997, Haala et al., 1998).

2 SEGMENTATION ALGORITHM

2.1 Theoretical Background

The arithmetic mean μ_a is defined in Equation (1)

$$\mu_a = \frac{1}{N} \cdot \sum_{i=1}^{N} s_i \tag{1}$$

where N is the total number of the LIDAR points s_i, with $i \in \{1, 2, \ldots, N\}$.

2.2 Proposed Algorithm

Another subsection ...

Test 1	Test 2	Test 3	Test 4
1	2	3	4
10	20	30	40

Table 1: Example 1 of a table

As listed in Table 1 and 2, respectively ...

Category	Producer	User
A	82.96%	86.54%
B	88.62%	86.01%
C	32.68%	35.05%
D	84.37%	83.99%

Table 2: Example 2 of a table

3 RESULTS AND DISCUSSION

The histogram of the LIDAR data tile in Figure 1 shows both classified ground (blue) and object (red) points. However, Figure 1 depicts the same histogram using subfigures in Figure 2(a) and 2(b), respectively.

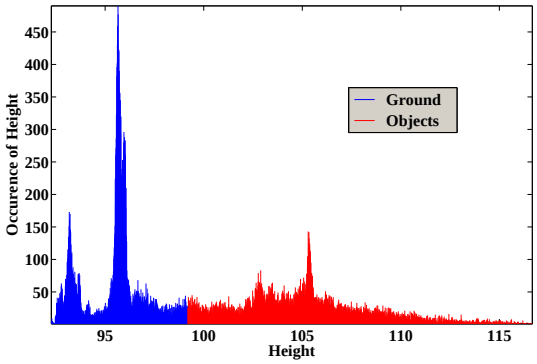
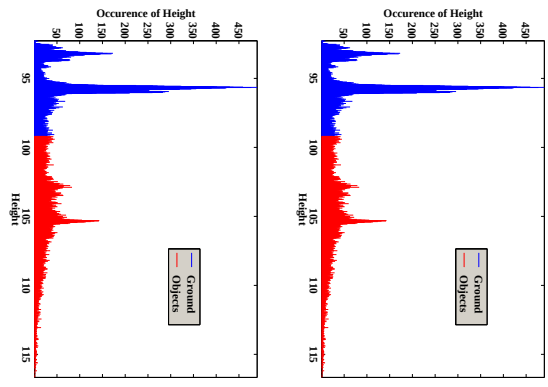


Figure 1: Histogram of classified points



(a) Histogram 1 (b) Histogram 2

Figure 2: Rotated histograms of classified points as subfigures

4 CONCLUSIONS AND FUTURE WORK

Conclusions and future work.

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