

Digital Photogrammetric System

PHOTOMOD

Version 8.0

USER MANUAL

LIDAR Data processing
(Windows x64)

Table of Contents

1. Purpose of the document	3
2. About	3
3. The “Load LAS” window	5
3.1. LIDAR data loading	9
3.2. LIDAR data rendering settings	14
3.2.1. Classes manager	15
3.3. Selecting point groups	15
3.3.1. Points selection settings	19
4. Operations with LIDAR data	21
4.1. Point cloud boundaries	21
4.1.1. Splitting into sheets	21
4.1.2. Point cloud cutting by polygons	23
4.2. Converting points cloud	25
4.2.1. Convert opened LAS to DEM	26
4.2.2. Convert LAS to DEM (from active profile resources)	29
4.2.3. True Ortho creation	35
4.2.4. Transformation of point cloud coordinate system	41
4.3. Data compression	44
4.4. LAS interpolation	46
4.5. Point cloud colorization by project images	50
4.6. Lidar point classification	52
4.6.1. Automatic classification by NDVI	53
4.6.2. Manual point groups classification	55
4.6.3. Switching classes	57
4.7. Building a histogram by a point cloud	59
5. LAS filtering	61
5.1. LAS filtering by elevations and numbers of reflected pulses	61
5.2. LAS smooth filter	65
5.3. LAS bilateral filter	66
5.4. LAS statistical outlier removal	68
5.5. LAS fusion	70
5.6. Buildings and vegetation filter	72
5.7. Manual deleting point groups	74
Appendix A. ASPRS Standard Point Classes	75

1. Purpose of the document

This document offers information on the processing point clouds stored in LAS format using *PHOTOMOD* software.



The *PHOTOMOD* software supports *ASPRS* (*American Society for Photogrammetry and Remote Sensing*) data format (from version 1.0 till version 1.4).

2. About

Lidar (also written LIDAR or LiDAR) is a remote sensing technology that measures distance by illuminating a target with a laser and analyzing the reflected light. Aerial LIDAR systems are represented by laser scanner for remote sensing of the earth's surface. *LIDAR data* – it is data obtained by lidar systems, which are installed on aircraft.

LIDAR data (and also some *point clouds*, which can be obtained from another sources) are delivered in LAS format files (from version 1.0 till version 1.4). LAS format files include the XYZ coordinates of the laser reflection points and their attributes (see the LAS [specification](#) published by *ASPRS* and the “[LIDAR data loading and displaying](#)” chapter of the current manual and [Appendix A](#)).

Points of the laser reflection from the earth's surface, which coordinates and attributes are contained in the LAS format files, is called the *LIDAR points* in this documentation.

The *PHOTOMOD* system also provides possibility to create a file of *point cloud* in the LAS format similar to LIDAR data (exceptions are described [below](#)). The point cloud creation in *PHOTOMOD* software is described in “Dense DEM generation using SGM method” chapter of the “[DTM Generation](#)” User Manual.

In most cases, the system supports the processing of LAS files regardless of the way the data was [received](#) (exceptions are described in an appropriate sections).

To work with lidar data and point clouds, use **Terrain** › **LAS** menu.

Table 1. Brief description of the “LAS” menu

Menu items	Function
 Loas LAS...	opens Load LAS window allowing to load LIDAR data
Cut LAS by polygons	to edit the area of point cloud coverage
Convert LAS-files to LAZ...	to create an archive file with the *.laz extension
Convert LAZ-files to LAS...	to extract an archive with the *.laz extension
Convert LAS to DEM	to convert LAS file(s) to DEM in batch mode
Convert LAS to TrueOrtho	to convert LAS file to TrueOrtho
LAS Interpolation	to change the detalization and the tile size of the LAS points cloud

Menu items	Function
Transform LAS coordinates	to change coordinate system of LAS
LAS filtering	to filter LIDAR data by numbers of reflected pulses in each point, by point classes and also by points elevations (especially using external DEM, to remove accident surges)
LAS smooth filter	to filter the points cloud, to remove such errors as a noise
LAS bilateral filter	to filter the points cloud, to remove such errors as a noise, taking into account points color (if such data are available in the LAS file)
LAS statistical outlier removal filter	to filter rough errors , i.e. single points beyond the main cloud at some distance from it, that are very likely erroneous data
LAS fusion filter	for point cloud filtering to remove noise taking into account averaged normals from processed points to projection centers of images used in their calculation (if such data are available in the LAS file)
LAS buildings and vegetation filter	Deletes points describing such objects as houses, trees, or cars. Only points describing the terrain remain in the cloud as a result of the filtering. The filter does not take into account the current classification of lidar points and analyzes only their mutual arrangement, which determines the shape of the surface described by the point cloud and its individual fragments
Colorization by project images	for colorizing a point cloud using project images
Classification by NDVI	for point classification according to NDVI index values, if the intensity of the reflected color values (in the infrared band) are available in the LAS file. This data is available in case if the input point cloud initially contains an IR channel (or was created using <i>PHOTOMOD</i> software tools from project images containing an IR channel)
Remap classes	to switch some classes of a classified point cloud to others

A point cloud cannot be loaded directly into the *PHOTOMOD* project and displayed in the 2D-window. A special **Load LAS** window is designed for working with point clouds (see below). The system also allows to open a point cloud with other layers in standard *PHOTOMOD* 3D window, from the file system or from the active profile resources (see the “[General information](#)” User Manual).



In most cases LAS files can be processed in the **Without project** mode (see the “[General information](#)” User Manual). Exceptions: **Colorization by project images**; optional – **Cut LAS by polygons** and **LAS filtering**.



The system allows to import lidar data as a vector layer (in the form of points, see the “Import from LAS” chapter of the “[Vectorization](#)” User Manual).

3. The “Load LAS” window

Load LAS window is used to load and transform the LIDAR data.

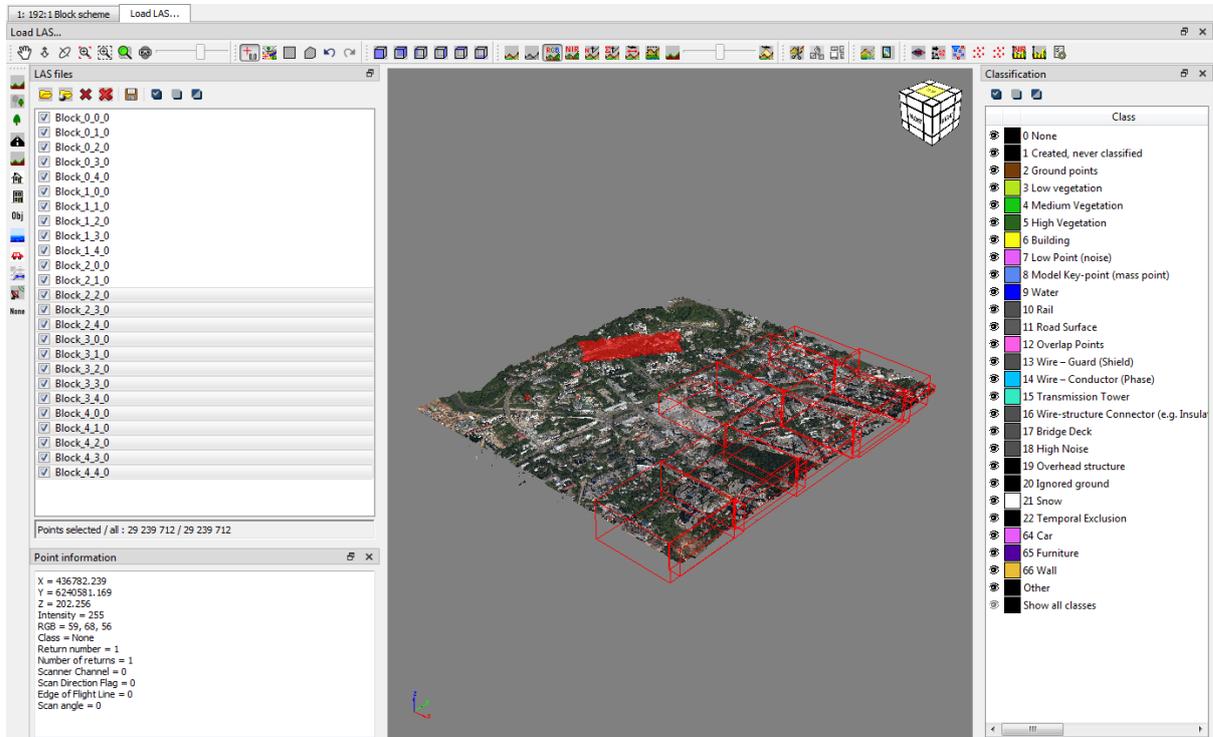


Fig. 1. The Load LAS window

Load LAS window contains the following GUI elements:

- the main toolbars which are used for viewing, editing, analysis and transforming LIDAR data (placed in the top of the window, by default);
- toolbar allowing to **classify** LIDAR points manually, in the left part of the window;
- toolbar for loading LIDAR data, in the left part of the window;
- the workspace with the list of all opened files, in the left part of the window;
 - the drop-down menu, allowing to view the information about loaded LAS-files and perform the **16 bit – 8 bit RGB conversion**.
- a workspace intended for displaying the total number of points in opened files, in the left part of the window;
- [optional] the **filter parameters** bar, allowing to specify the algorithm for selecting groups of points, in the left part of the window;

- [optional] the bar, intended for displaying information about the selected LIDAR point, in the left part of the window;
- working area for LIDAR points viewing, in the center of the window. This area contains in lower left corner the direction axes of the coordinate system of loaded point cloud;
- **classes manager** bar, in the right part of the window.



The system interface is flexible for customizing the locations of additional toolbars according to the user's needs. Additional toolbars can either be fixed in designated sections of the work area (top or bottom, right or left) or undocked by the user and placed in any place in the **Load LAS** window.

Depending on the user-set interface configuration, docked additional toolbars can be partly minimized (some buttons will be hidden). Docked (optionally minimized) subtoolbars are displayed as one line, vertical or horizontal, depending on their location.

By default, additional toolbars are docked at the top of the workspace, to the right of the main toolbar. Additional toolbars are marked with a special icon  located on the left or top (depending on the location) edge of the panel. To maximize the toolbar, click  () on the right (at the bottom).

Undocked additional toolbars are always displayed horizontally, in one line, in a fully maximized form. To undock a toolbar (or pinpoint it in any place), move the cursor over the  icon and, holding down the **left mouse button**, drag the toolbar to the area of its targeted location (the cursor's shape changes  when it is possible to capture the toolbar).

Table 2. The main toolbars, allowing to view and edit LIDAR data

Buttons	Functions
	to move working area for <i>LIDAR points</i> viewing in any direction
	to move working area for <i>LIDAR points</i> viewing perpendicular to the screen plane
	to enable rotation mode and rotate <i>LIDAR points</i>
	to zoom in/zoom out working area
	to zoom in of working area selected by rectangle
	to display data in full scale and center it in the window
	turns on/off stereomode (anaglyph or page-flipping, see the "Stereo settings" chapter in "General system's parameters" User Manual)
	is used for the parallax management when the stereomode is on

Buttons	Functions
	to display information about the selected LIDAR point
	to enable the mode for selecting lidar points located adjacent to each other and presumably having the same origin
	to select a group of lidar points inside a rectangle
	to select a group of lidar points inside arbitrary polygon
	to cancel the last editing operation

Buttons	Functions
	to redo the last undone operation
	to save selection to resource
	to delete selection

Buttons	Functions
	to rotate <i>LIDAR points</i>

Buttons	Functions
	to display <i>LIDAR points</i> in coloring mode to accordance with its Z-coordinate values
	to display <i>LIDAR points</i> in coloring mode to accordance with intensity (the return strength of a laser beam per one point), if source LAS file contains such data
	to display <i>LIDAR points</i> in RGB mode (if source LAS file contains such data)
	to display <i>LIDAR points</i> in near-infrared mode (if source LAS file contains such data)
	to display <i>LIDAR points</i> in coloring mode to accordance with serial number of reflected pulse per one point (if source LAS file contains such data)
	to display <i>LIDAR points</i> in coloring mode to accordance with number of reflected pulses per one point (if source LAS file contains such data)
	to display <i>LIDAR points</i> in coloring mode to accordance with scan direction (if source LAS file contains such data)
	to display <i>LIDAR points</i> in coloring mode to accordance with edges (if source LAS file contains such data)
	to display <i>LIDAR points</i> in coloring mode to accordance with objects classification (if source LAS file contains such data). Lidar point colors according to the classification are displayed over RBG lidar point colors (if such data is available in the LAS file)
	to customize lidar point color opacity when the coloring mode according to the object classification () is switched on. To change the opacity of point coloring according to the classification, move the slider to the right relative to the original (central) position. To change the opacity of the RGB coloring, move the slider to the left relative to the original position. Changing opacity is not available for other lidar data coloring modes.
	to display <i>LIDAR points</i> in coloring mode to accordance with scan angle (if source LAS file contains such data)

Buttons	Functions
	to split the loaded LIDAR data
	to enable/disable displaying of splitting grid
	to save parts of LIDAR data corresponding to created splitting into separate LAS files

Buttons	Functions
	to convert to DEM all the point clouds, which are displayed in working area in the right part of the window
	to convert to TrueOrtho all the point clouds, which are displayed in working area in the right part of the window

Buttons	Functions
	to change the detalization and the tile size of the LAS points cloud
	to change coordinate system of LAS
	to filter LIDAR data by numbers of reflected pulses in each point, by point classes and also by points elevations (especially using external DEM, to remove accident surges)
	to filter the points cloud, to remove such errors as a noise
	for point cloud filtering to remove noise taking into account averaged normals from processed points to projection centers of images used in their calculation (if such data are available in the LAS file)
	to create a histogram , according to LIDAR points NDVI index, if the intensity of the reflected color in the infrared band values (which are involved in NDVI index calculation) are available in the LAS file
	to create a histogram , according to LIDAR points classification (if such data are available in the LAS file)
	to configure loaded LAS settings in the workspace to display lidar points

Table 3. Toolbar allowing to classify LIDAR data

Buttons	Functions
	assign the low vegetation standard class to manually selected () lidar points (3)
	assign the medium vegetation standard class to manually selected lidar points (4)
	assign the high vegetation standard class to manually selected lidar points (5)
	assign the road surface standard class to manually selected lidar points (11)
	assign the ground standard class to manually selected lidar points (2)
	assign the building standard class to manually selected lidar points (6)
	assign the wall class to manually selected lidar points (66). This class is used in <i>PHOTOMOD</i> and is not a part of the <i>ASPRS</i> -developed standard classification . <i>PHOTOMOD</i> software uses one of the user definable classes, considering it as wall , inside the <i>PHOTOMOD</i> system
	assign the furniture class to manually selected lidar points (65). This class is used in <i>PHOTOMOD</i> and is not a part of the <i>ASPRS</i> -developed standard classification. <i>PHOTOMOD</i> software uses one of the user definable classes, considering it as furniture , inside the <i>PHOTOMOD</i> system
	assign the water standard class to manually selected lidar points (9)
	assign the car class to manually selected lidar points (64). This class is used in <i>PHOTOMOD</i> and is not a part of the <i>ASPRS</i> -developed standard classification. <i>PHOTOMOD</i> software uses one of the user definable classes, considering it as car , inside the <i>PHOTOMOD</i> system
	assign the wire - conductor (phase) standard class to manually selected lidar points (14)

Buttons	Functions
	assign the transmission tower standard class to manually selected lidar points (15)
	assign the Created, never classified standard class to manually selected lidar points (0)

Table 4. Toolbar allowing to load LIDAR data

Buttons	Functions
	to open the LAS format files with LIDAR data located in a folder of <i>Windows</i> file system
	to open the LAS format files with LIDAR data located in active profile resources
	to close selected LAS format files with LIDAR data
	to close all opened LAS format files with LIDAR data
	to save the selected point cloud areas as a separate files in the active profile resources
	to select all items in the list of all opened files
	to deselect all items in the list
	to invert items selection

3.1. LIDAR data loading

In order to load and display LIDAR data perform the following actions:

1. Choose **Terrain** › **LAS** › **Load LAS....** The **Load LAS** window opens.
2. Perform one of the following actions:
 - [optional] Click the  button to load files located in a folder of *Windows* file system;
 - [optional] Click the  button to load files located in active profile resources.

The list of loaded files is displayed in the workspace, in the left part of the window. To show (or hide) data from loaded files in the workspace located in the right part of the window, set (or clear) the appropriate checkboxes.

Use the **left mouse button** to select loaded files (point cloud tiles) in the work area with the list of loaded files.

To view the information on downloaded LAS-files, select the appropriate files in the workspace with a list of downloaded files by clicking the left mouse button and open the drop-down menu by clicking the right mouse button. Choose **LAS files info** to open the window containing information about the points number in every opened LAS-file.

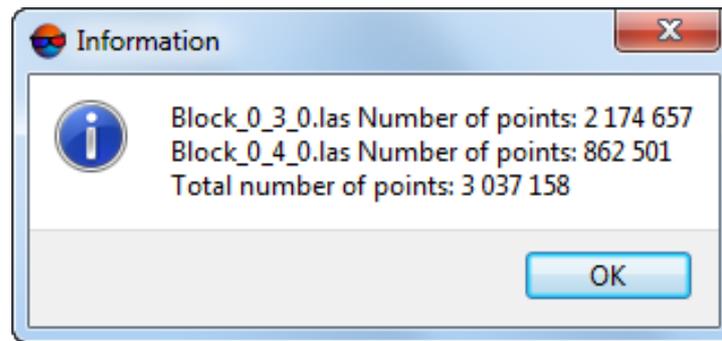


Fig. 2. The Information window

The number of points in the loaded LAS files is also displayed in the workspace in the left part of the window directly under the list of loaded files. Two parameters are displayed in this workspace:

- **Points (all)** – is the sum of points in all the loaded LAS files;
- **Points (selected)** – is the total number of points contained in the clouds intended for visual display in the workspace located in the right part of the window.



To display any given point cloud in the workspace in the right part of the window, set the appropriate checkbox in the list of loaded LAS files.

To convert 16-bit color LAS-files, select the appropriate files in the workspace with a list of downloaded files and open the drop-down menu by clicking the right mouse button and enable the mode that allows to perform **16 bit – 8 bit RGB conversion**.



For invert conversion, disable the mode that allows to perform **16 bit – 8 bit RGB conversion**, by re-selecting the appropriate item in the drop-down menu.

System provides the following features to control the display of loaded *LIDAR points*:

- use the mouse wheel for scaling points or use , ,  and  buttons;
- click the  button and move cursor in the working area with the pressed left mouse button to rotate or use , , ,  and  buttons;

To display information about a point of interest set the point selection mode () and select a point in working area for LIDAR points viewing (by mouse left click). The following data appears in lower left corner of the **Load LAS** window (if LAS file contains such data):



Together with a lidar point in the view area, the appropriate LAS-file to which this point belongs is selected.

- Coordinates, **X, Y, Z**;



Click the  button to enable the height coloring mode.

- The **Intensity** value – the integer representation of the pulse return magnitude;



Click the  button to enable the intensity coloring mode.



For a so-called “photogrammetric” point cloud (e.g., *PHOTOMOD*-created), the intensity means the value of the color brightness for the given point (see the next section).

- **RGB** or **RGBN** values (if LAS file contains NIR channel);



Click the  button to enable the RGB coloring mode.



Click the  button to display LIDAR points in near-infrared mode (if LAS file contains NIR channel).



The IR band is supported e.g. for some data record formats in v1.4 LAS files (Point Data Record Format 8). Format and version of initial LAS files depend on data provider. For more info see *ASPRS* v1.4 LAS specifications.

PHOTOMOD also provides for creating a point cloud that contains detailed data (if initial images have an IR band, see “Dense DEM generation using SGM method” in the “[DTM Generation](#)” User Manual).

- [optional] **NVDI** value (if LAS file contains NIR channel);



NDVI is the normalized difference *vegetation index*. Vegetation index is a numerical indicator of the quality and quantity of vegetation in the studied area.

NDVI is one of the most widely used vegetation indices. It is the ratio between the difference in the intensities of reflected light in the red (Red) and near infrared (NIR) bands and their sum:

$$NDVI = (NIR - RED) / (NIR + RED)$$



PHOTOMOD provides for classifying lidar points according to *NDVI* (see the “[Classification by NDVI](#)” chapter).



It should be taken into account that the intensity of the reflected color in the infrared band and the **point class** (see below) are the properties of a lidar point, that (optionally, if such data are available) can be recorded in a LAS file, unlike the *NDVI* index, which is calculated by the system when accessing a particular point selected by the user.

- **Class** – see the LAS [specification](#) published by *ASPRS* and [Appendix A](#).



Click the  button to enable the coloring mode to accordance with objects classification.



The value of the **point class** parameter initially depends on the data provider (the point may be not classified), and later on - on the subsequent processing that the point cloud is subjected to (for example, lidar point **classification** according to the NDVI index, using the *PHOTOMOD* software, performed with user settings).

Thereof, in the latter case (depending on the settings specified by the user during the latest classification) the mutual **ratio** of the current **point class** and the calculated NDVI index may not comply with common standards.



Classes assigned to DEM cells are automatically considered during DEM conversion in a LAS point cloud (see “DEM classification” and “Convert DEM to point cloud (LAS)” in the “**DTM Generation**” User Manual).

- [optional] **Normal direction** from point to projection centers of images, used in calculation of the current point (only if LAS file was created in *PHOTOMOD* software, see the “Dense DEM generation using SGM method” chapter of the “**DTM Generation**” User Manual and the “**LAS fusion**” chapter of current manual);
- **Classification flags** – see the “LAS Specification 1.4” published by *ASPRS*;
- **Return number** – see the “LAS Specification 1.4” published by *ASPRS*;



Click the  button to enable the coloring mode to accordance with serial number of reflected pulse per one point.



Service data used by the system are recorded as the **return number** parameter values in the point cloud created by *PHOTOMOD*.

- **Number of returns** – see the “LAS Specification 1.4” published by *ASPRS*;



Click the  button to enable the coloring mode to accordance with number of reflected pulses per one point.



In case of the cloud of points, created during the DEM creation using the SGM method, the number of reflected pulses in the given point () is the number of stereopairs on the basis of which a particular point was calculated: 1, 2, 3, 4, 5, 6, 7, or 8. Limitation of the “number of reflected pulses” by 1 to 8 results from the limitations of the LAS format itself, accordingly, in the latter case, the number of stereopairs can be both “8” and “8 and more”.

Table 5. Points coloring modes

Point color	 Number of reflected pulses per point	 Serial number of reflected pulse
■	no data available	no data available
■	1	1
■	2	2
■	3	3
■	4	4
■	5	5

Point color	 Number of reflected pulses per point	 Serial number of reflected pulse
	6	6
	7	7
	8 or more	8

- **Scanner channel** – see the “LAS Specification 1.4” published by *ASPRS*;
- **Scan Direction Flag** – see the “LAS Specification 1.4” published by *ASPRS*;



Click the  button to enable the coloring mode to accordance with scan direction.

- **Edge of Flight Line** – see the “LAS Specification 1.4” published by *ASPRS*;
- **Scan angle** – see the “LAS Specification 1.4” published by *ASPRS*.



Click the  button to enable the coloring mode to accordance with scan angle.

When viewing and analyzing the lidar point attributes listed above, take into account the following:

- The origin of the data — whether the point cloud in question was obtained as a result of laser scanning or whether it is “photogrammetric” (i.e., created using some digital photogrammetric system tools, *PHOTOMOD*, for example):
 - When working with point clouds obtained directly as a result of laser scanning, it is necessary to take into account the characteristics of a particular data provider, for example, the LAS format version used, which may determine the classification of points used in a given specific case, as well as the availability (or absence) of certain data (recorded in the attributes of points);
 - When working with so-called “photogrammetric” point clouds, note that data recorded as the values of such attributes as, for example, the **Intensity** or **Number of Reflections**, have different physical senses (see above), unlike similar point attribute values in a cloud that were obtained in a standard way (see the previous paragraph).
- Operations with lidar data previously performed on the point cloud under consideration (filtering, interpolation, point classification and reclassification, and point cloud colorization based on project images, etc.):
 - Operations that include data filtering (interpolation) imply rearrangement of the point cloud, both deleting old points and creating new ones, with some “average”

values of some attributes, calculated according to the data processing algorithms used;

- Previously performed point cloud classification (reclassification) operations could have resulted in the assignment of arbitrary classes to certain point groups based only on the user's choice;
- While performing certain operations, some attributes of the points under processing can be **overwritten**, by the user's choice.

3.2. LIDAR data rendering settings

To configure the display settings for downloaded point clouds in the workspace (3D-scene) of the **Load LAS** window, click the  button in the toolbar of this window. The **Settings** window opens:

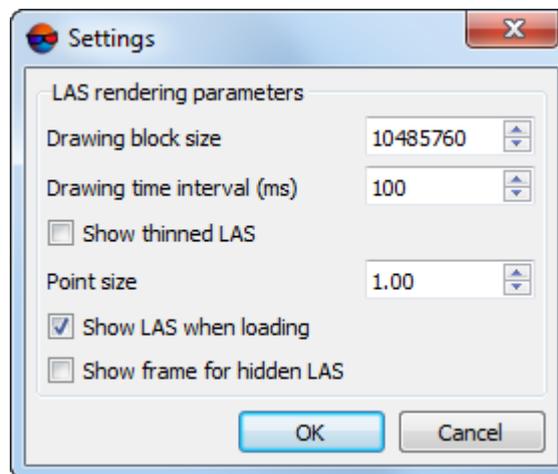


Fig. 3. The Settings window

Set the following options in the **Settings** window:

- **Drawing block size** (points number);
- **Drawing time interval** (ms);
- **Point size**;
- To **show thinned LAS**, set the appropriate checkbox;
- To **show LAS when loading**, set the appropriate checkbox;
- To **show frame for hidden LAS**, set the appropriate checkbox.

Click OK. Rebuilding of the loaded LAS starts in the workspace of the **Load LAS** window.

3.2.1. Classes manager

In the classes manager is displayed the list of all available classes (see [Appendix A](#)) and the following elements of classes management:

-  – the current points class is visible in working area for LIDAR points viewing, in the central part of the window;
-  – the points of the current class are invisible.



Click the  button to set the appropriate class visibility.

The classes manager toolbar contains the following elements:

-  – allows to select all items;
-  – allows to deselect all items;
-  – allows to invert items selection.

3.3. Selecting point groups

The system provides the following modes of group lidar point selection for their further [deletion](#), [manual classification](#) or saving as a separate files in the active profile resources.

Table 6. Main “Load LAS”, toolbar buttons intended for group selection of lidar points

Buttons	Functions
	to enable the mode for selecting lidar points with similar color characteristics located adjacent to each other and presumably having the same origin
	to select a group of lidar points inside a rectangle
	to select a group of lidar points inside arbitrary polygon

The system provides an algorithm for selecting groups of points located adjacent to each other, and, presumably, describing some separate, distinct object. Both point attributes and their mutual arrangement are to be analyzed there.

To do this, perform the following:

1. Click the  button in the **Load LAS** window toolbar to enable the mode for selecting lidar poing groups presumably having the same origin;
2. [optional] [configure](#) the algorithm for point group selection in the appropriate section of **Load LAS** window;

3. To select a point group, move mouse cursor over the appropriate area of the point cloud in the work area intended for lidar point display in the right part of the **Load LAS** window and click it by the **left mouse button**. The area of the point cloud (selected according to the search algorithm and the [specified settings](#)) is highlighted using a color fill);
4. [optional] To add another one (or more) point cloud areas to the selected one, move the marker and click desired point cloud areas by the **left mouse button** holding down **Shift**;
5. [optional] To cancel selection, press **Esc**. If several areas of the point cloud were selected at once (see the previous paragraph), then the selection would be cancelled from the last selected area in turn. In this case, to cancel the selection on the whole, press **Esc** the appropriate number of times (or start the process of selecting areas of the point cloud again without holding **Shift**;
6. Make sure that the desired areas of the point cloud are highlighted with color fill.

The system allows user also to select lidar points inside a rectangular polygon. For this, perform the following:

1. Click  in the **Load LAS** toolbar;
2. [optional] [configure](#) the algorithm for point group selection in the appropriate section of **Load LAS** window – in order not to add points which are “invisible” to a user under condition of current arrangement of the set of lidar data, set the **check hidden zones in selection process** checkbox;
3. To select lidar points, press and hold the **left mouse button** and “stretch” the rectangle in the work area with lidar points. The area of the point cloud (selected according to the [specified settings](#)) is highlighted using a color fill);
4. [optional] To add another one (or more) point cloud areas to the selected one, repeat the steps from the above paragraph holding **Shift**;



To subtract some points from the selection, repeat the steps from the above paragraph holding **Shift+S**.



To select the points, located in the intersection between the previous selection and the current selection area, repeat the steps from the above paragraph holding **Shift+C**.

5. [optional] To cancel selection, press **Esc**. If several areas of the point cloud were selected at once (see the previous paragraph), then the selection would be cancelled from the last selected area in turn. In this case, to cancel the selection on the whole, press **Esc** the appropriate number of times (or start the process of selecting areas of the point cloud again without holding **Shift**;

6. Make sure that the desired areas of the point cloud are highlighted with color fill.

To select lidar points within an arbitrary-shaped polygon, perform the following:

1. Click  in the **Load LAS** toolbar;
2. [optional] [configure](#) the algorithm for point group selection in the appropriate section of **Load LAS** window – in order not to add points which are “invisible” to a user under condition of current arrangement of the set of lidar data, set the **check hidden zones in selection process** checkbox;
3. Create a polygon moving the cursor step-by-step in the work area with lidar points and pressing the **left mouse button**. The created polygon is visually displayed with dashed gray lines. To complete the rectangle creation, press **Enter** (or create the last rectangle’s vertex by double-click of the **left mouse button**). The area of the point cloud (selected according to the specified settings) is highlighted using a color fill);
4. [optional] To add another one (or more) point cloud areas to the selected one, repeat the steps from the above paragraph holding **Shift**;



To subtract some points from the selection, repeat the steps from the above paragraph holding **Shift+S**.



To select the points, located in the intersection between the previous selection and the current selection area, repeat the steps from the above paragraph holding **Shift+C**.

5. [optional] To cancel selection, press **Esc**. If several areas of the point cloud were selected at once (see the previous paragraph), then the selection would be cancelled from the last selected area in turn. In this case, to cancel the selection on the whole, press **Esc** the appropriate number of times (or start the process of selecting areas of the point cloud again without holding **Shift**;
6. Make sure that the desired areas of the point cloud are highlighted with color fill.

The selection snaps into action only for points visually displayed in the viewing area (point group display is managed at the level of individual files; see [Section 3.1](#)). Hence, to select a group of points belonging to a certain file (e.g., to one of the tiles that a large point cloud is divided into), perform the following:

1. Disable the visibility of neighboring point cloud tiles;

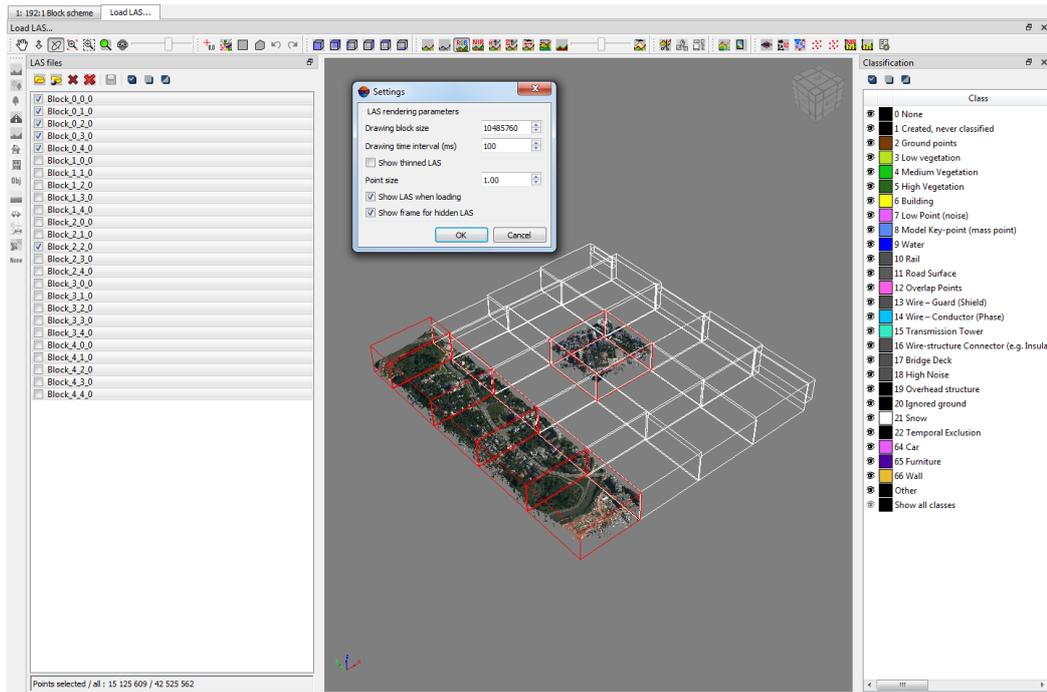


Fig. 4. The Load LAS window (the visibility of tiles neighboring the desired one is disabled)

2. Select point of the remaining tile (or tiles) using appropriate tools (☐, ☐);

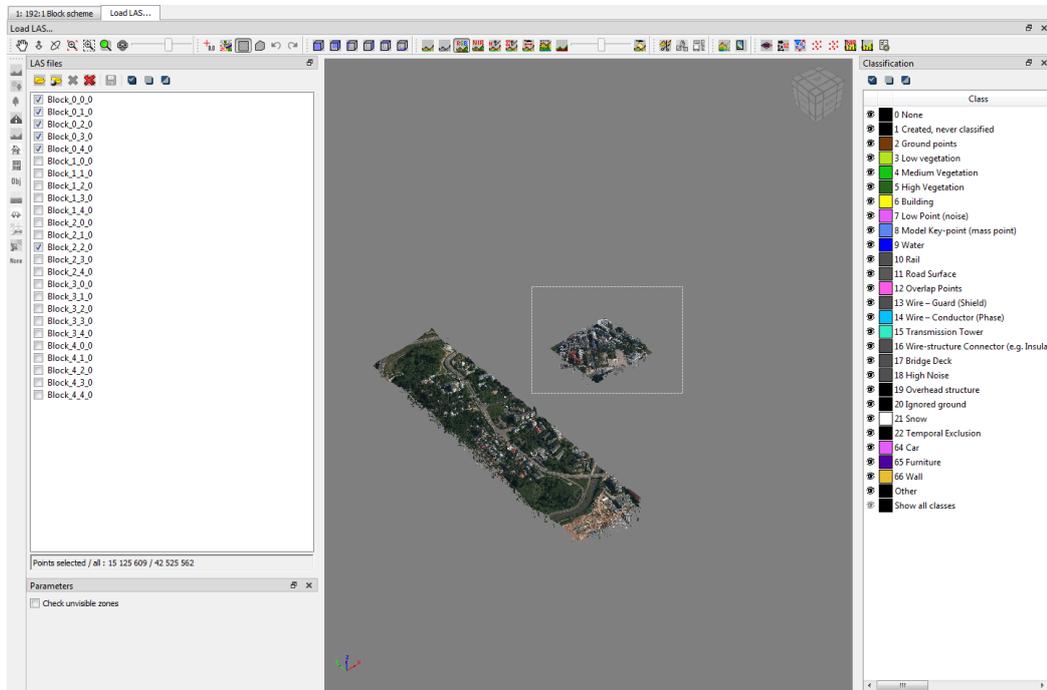


Fig. 5. The Load LAS window (selecting points contained in the desired tile)

3. Enable the visibility for previously disabled tiles.

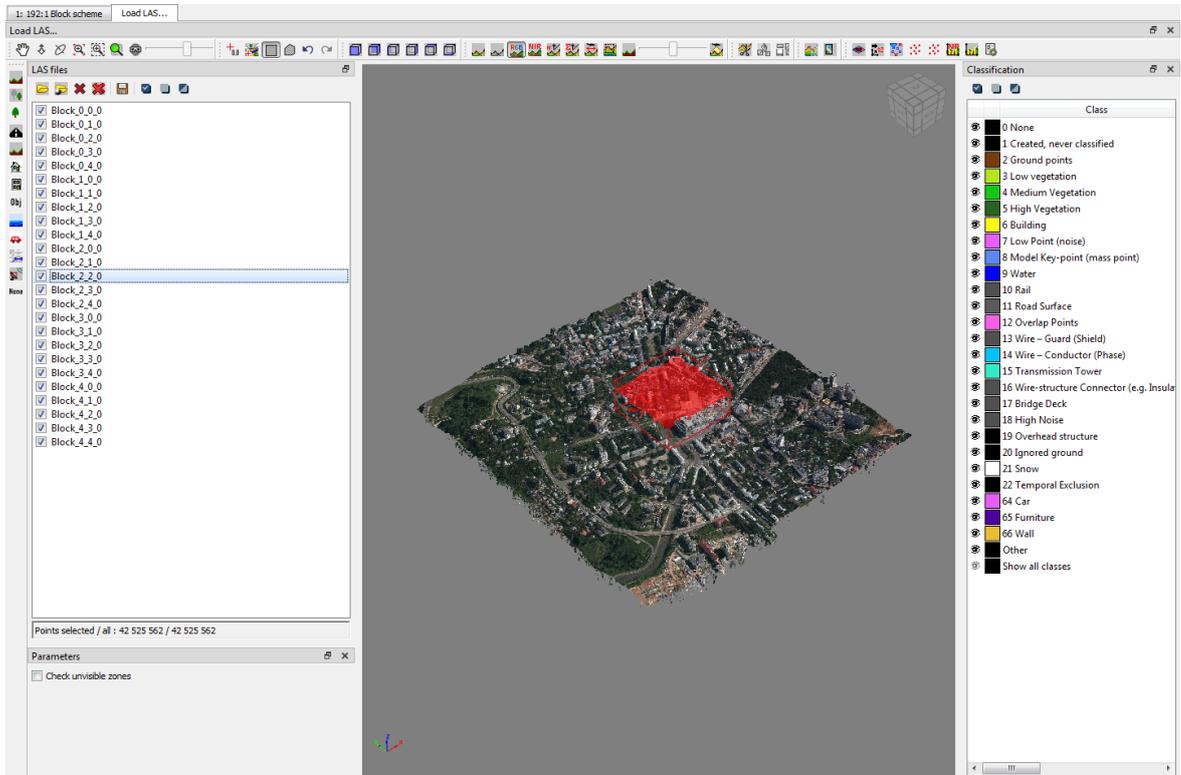


Fig. 6. The Load LAS window (the selected points are located within the relevant tile)

3.3.1. Points selection settings

The filter **parameters** bar, allowing to specify the algorithm for selecting groups of points, is situated in the left part of the **Load LAS** window, by default:

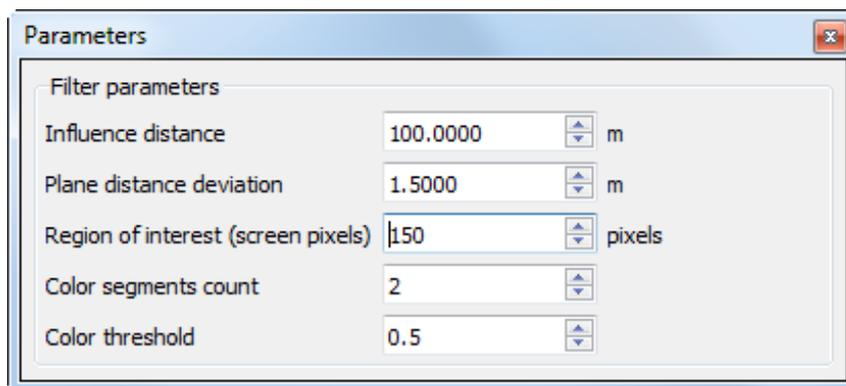


Fig. 7. The Filter parameters bar (the adjacent points selection mode)

The system provides to specify the algorithm for selecting groups of points located adjacent to each other (🇬🇧):

- **Max selection distance**, in project units;
- **Max height difference**, in project units;
- **Search region in screen coordinates**, in pixels;
- **Color segments count** (from 2 to 10) into which the point cloud will be split during analysis while selecting a cloud fragment;



In this case, a color segment is a group of points having similar color characteristics. For example, if the **Color segments count** is equal to 2, then during analysis, all cloud points will be divided into two groups according to their color characteristics, taking into account the **Color threshold** (see below).

It should be considered that the actual size of the selected point cloud fragment depends not only on the color characteristics of the points themselves and the level of detail with which the cloud points were grouped according to their colors, but also on the characteristics described above that determine the size of the search area for similar points (**Max selection distance**, **Search region in screen coordinates**).

- **Color threshold** (the higher its value, the stricter the merging conditions are).

Set the **check invisible zones** checkbox when selecting lidar points within polygons (□, ◻), in order not to add points which are, “invisible” to the user under condition of current arrangement of the set of lidar data (in the **Load LAS** work area supposed for lidar point viewing).

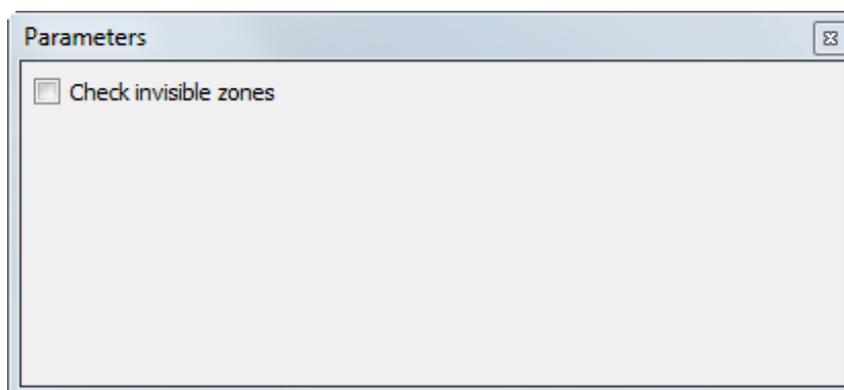


Fig. 8. The Filter parameters bar (the adjacent points selection mode)



The button of the main **Load LAS** toolbar enables the mode of rotating the lidar data set in an arbitrary way.

4. Operations with LIDAR data

4.1. Point cloud boundaries

4.1.1. Splitting into sheets

The system provides the splitting into sheets of loaded LIDAR data to save data in the separate LAS format files or to select one or another parts of source LAS format file for DEM building.

To split the LIDAR data into sheets do the following actions:

1. Click the  or  button to load files. Choose one or more files in LAS format and click OK.
2. Choose one or more files in LAS format and click the  button to specify splitting settings. **Splitting settings** window opens.

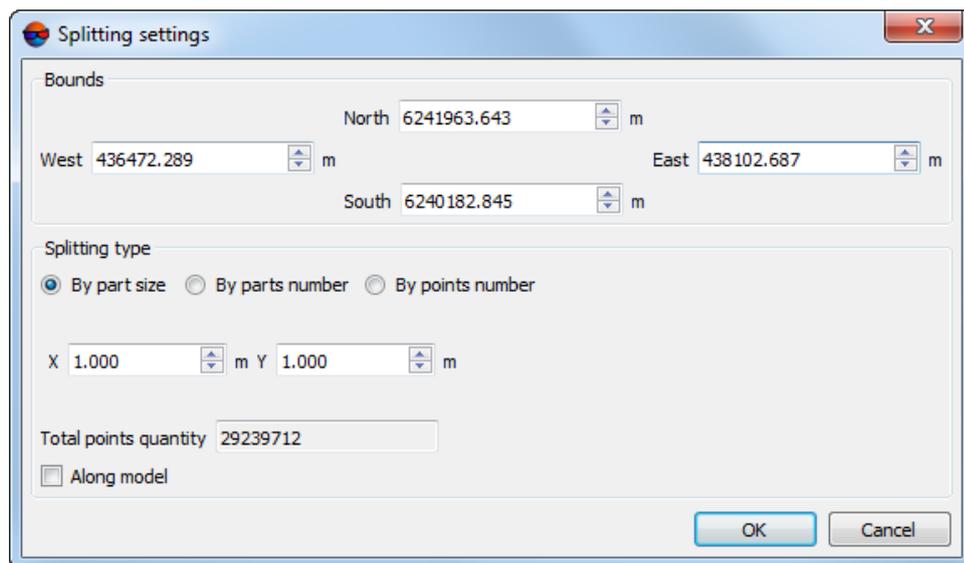


Fig. 9. The Splitting settings window



The window displays the values of the lidar data area boundaries, in the **Bounds** section.

3. In the **Splitting type** panel select the splitting type by check box and specify the parameters:
 - **By part size** – splitting sheet's size along X and Y axes in meters defines;
 - **By parts number** – number of splitting sheets along X and Y axes defines;

- **By points number** – max number of *LIDAR points* per single splitting sheet in the **Max points per single file** entry field.
4. [optional] To split data along extended fringe of model, set the **Along model**.
 5. Click OK. **Splitting settings** window closes. Sheet frames for selected file are displayed in **Load LAS** window.



Use the  button for turning on/off the sheet frames displaying mode.

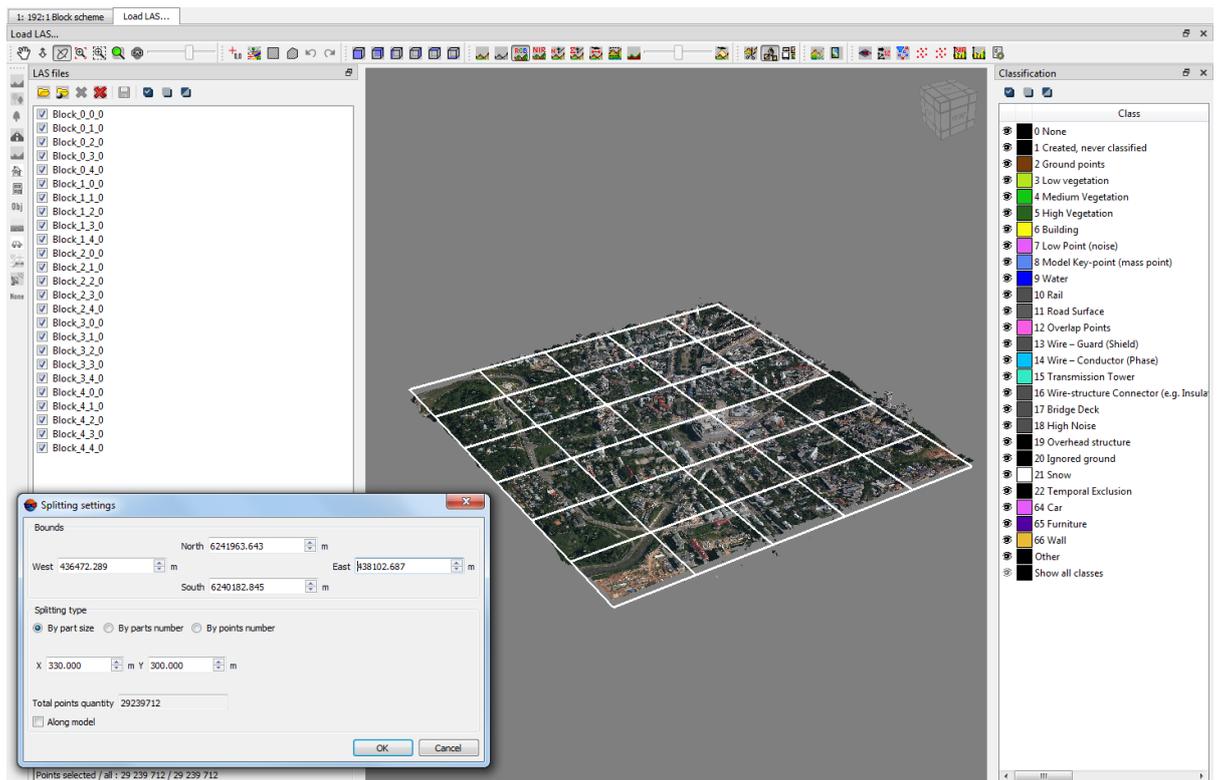


Fig. 10. The Splitting sheets displaying

6. Click the  button to save the LIDAR data from splitting sheets in the separate LAS format files. **Save** window opens.
7. Specify the folder of active profile and *left part* of the name for creating the LAS format files.
8. Click OK. The file is created for each sheet. The name of this file is created from the specified initial part, the filename of splitting of LIDAR data and the serial number in accordance with the number of the splitting sheets.

4.1.2. Point cloud cutting by polygons

The system allows to edit the area of point cloud coverage.



The most typical example of using this functionality is the need to cut out from a large point cloud describing a certain area of terrain several separate fragments describing areas of interest to the user (for example, areas located within the boundaries of certain populated areas).

The point cloud under processing is supposed to be created through the “photogrammetric” way (see “Dense DEM generation using SGM method” in the “[DTM Generation](#)” User Manual) using the material of the same project in which the vector polygons that confine the areas of interest were created.

The system also allows using polygons created within a copy of the original project (in which the LAS point clouds were created), which differs from the original project in the results of triangulation point measurements, adjustments, and/or the current coordinate system. This allows avoiding unnecessary time costs when re-creating a point cloud.

To do this, perform the following actions:

1. Create vector layer with polygons in active profile resources (see the “[Vectorization](#)” User Manual);
2. Make sure, that the polygons used as boundaries have the joint additional *text* attribute with the unique values for the every polygon.

Name of output point cloud fragment (LAS-files and also names of output folders containing these LAS-files) are to be set automatically from the unique attribute value of the polygon used as boundary for cutting.



The use of numeric attributes (float, integer) is not allowed for this operation.



Every polygon must have the unique value.

3. [optional] Load the project in the framework of which polygons planned for use were created (in the case if the LAS point cloud and polygons had been created in different project copies);
4. Select **Terrain > LAS > Cut LAS by polygons**. The **Cut LAS by polygons** window opens:

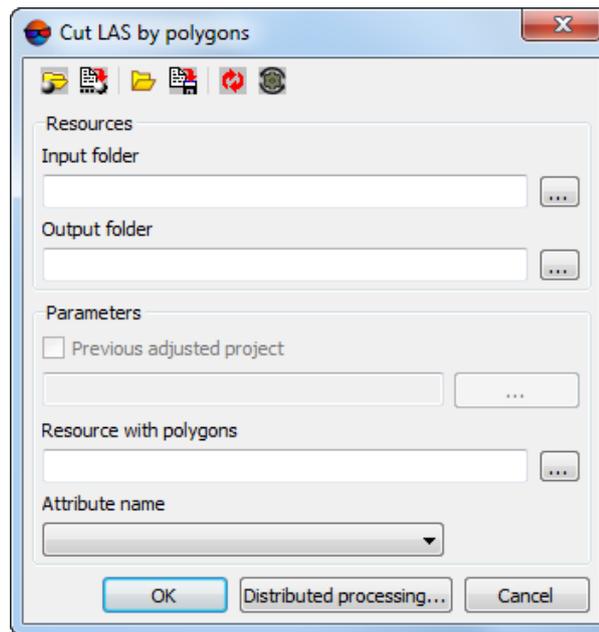


Fig. 11. Parameters of cutting by polygons

A toolbar in the upper part of the window is intended to save/load parameter's settings and contains the following buttons:

-  – allows to load parameter's settings saved previously to active profile resources;
-  – allows to save all parameter's settings to *.x-ini file located in active profile resources;
-  – allows to load parameter's settings from *.x-ini file located in a folder of Windows file system;
-  – allows to save parameter's settings to *.x-ini file located in a folder of Windows file system;
-  – allows to restore the last-session's settings;
-  – allows to restore default parameter's settings.

5. In the **Resources** section click the  button in the **Input folder** field to select input folder with LAS-files in active profile resources;
6. In the **Resources** section click the  button in the **Output folder** field to specify output folder, containing folders with output LAS-files in active profile resources;

7. [optional] To define a **Previous adjusted project** in active profile resources, set the appropriate checkbox and click the appropriate  button. Specify the project where the LAS point cloud was created.



This operation may be required if the project (or its copy) was readjusted after the LAS-file creation (see above).

8. To define the vector layer with polygons used as boundaries in active profile resources, click the  button in the **Resource with polygons** field;
9. Select the **Attribute name** of polygons used as boundaries in appropriate drop-down list;
10. Click OK.

To edit DEM in distributed processing mode, perform the following actions:

1. Change settings and run the distributed processing server/client (see the “Distributed processing” chapter in the “[General information](#)” User Manual).
2. Click the **Distributed processing** button. Distributed processing tasks are created. Number of created tasks matches with number of LAS-files.

4.2. Converting points cloud

To use lidar data in in *PHOTOMOD* system, it is necessary to convert it. The system allows for the following:

- Convert point clouds opened in the **Load LAS** window into a DEM (see [Section 4.2.1](#));
- Convert point clouds loaded into active profile resources into a DEM (see [Section 4.2.2](#));
- Convert lidar data into True Ortho Ortho (see [Section 4.2.3](#)).



A point cloud cannot be loaded directly into the *PHOTOMOD* project and displayed in the 2D-window. A special **Load LAS** window is designed for working with point clouds (see above). The system also allows to open a point cloud with other layers in standard *PHOTOMOD* 3D window, from the file system or from the active profile resources (see the “[General information](#)” User Manual).



The system allows to import lidar data as a vector layer (in the form of points, see the “Import from LAS” chapter of the “[Vectorization](#)” User Manual).

4.2.1. Convert opened LAS to DEM

The system allows to convert all point clouds opened in **Load LAS** window into single DEM.



Point clouds will be transformed into a single DEM. Only the clouds displayed in the workspace in the right part of the **Load LAS** window will be transformed.



To display any given point cloud in the **Load LAS** workspace, set the appropriate checkbox in the list of loaded LAS files.



Coordinate system change is not available in the case of rapid transform of LAS files started from the toolbar of the **Load LAS** window.

To do so perform the following actions:

1. **Load Lidar data.**
2. Click the  button. The **Save** window opens. Define folder in the active profile and filename of output DEM in the **Save** window. Click **Save**.
3. The **Convert LAS to DEM** window opens. **Estimated DEM size, width, height, and boundaries** will be calculated in the **Convert LAS to DEM** window:

Fig. 12. The Convert LAS to DEM window

4. [optional] Specify the **DEM cell size** in meters. Automatic recalculation of the **Estimated DEM size** is performed while change the **DEM cell size**;
5. Set the DEM building **parameters**:
 - To **use interpolation** set an appropriate checkbox and specify the **interpolation radius** in project units;
 - Select the **build method**:
 - **Average**;
 - **Select value from max height point**;
 - **Select max weight point**;
 - **Select point with max quality**.
6. [optional] set the **Classification filter** checkbox to set LAS preliminary filtering parameters according to the classification of points (see the LAS [specification](#) published by *ASPRS* and [Appendix A](#));

Click **Select classes**. The **LAS classification filter parameters** window opens:

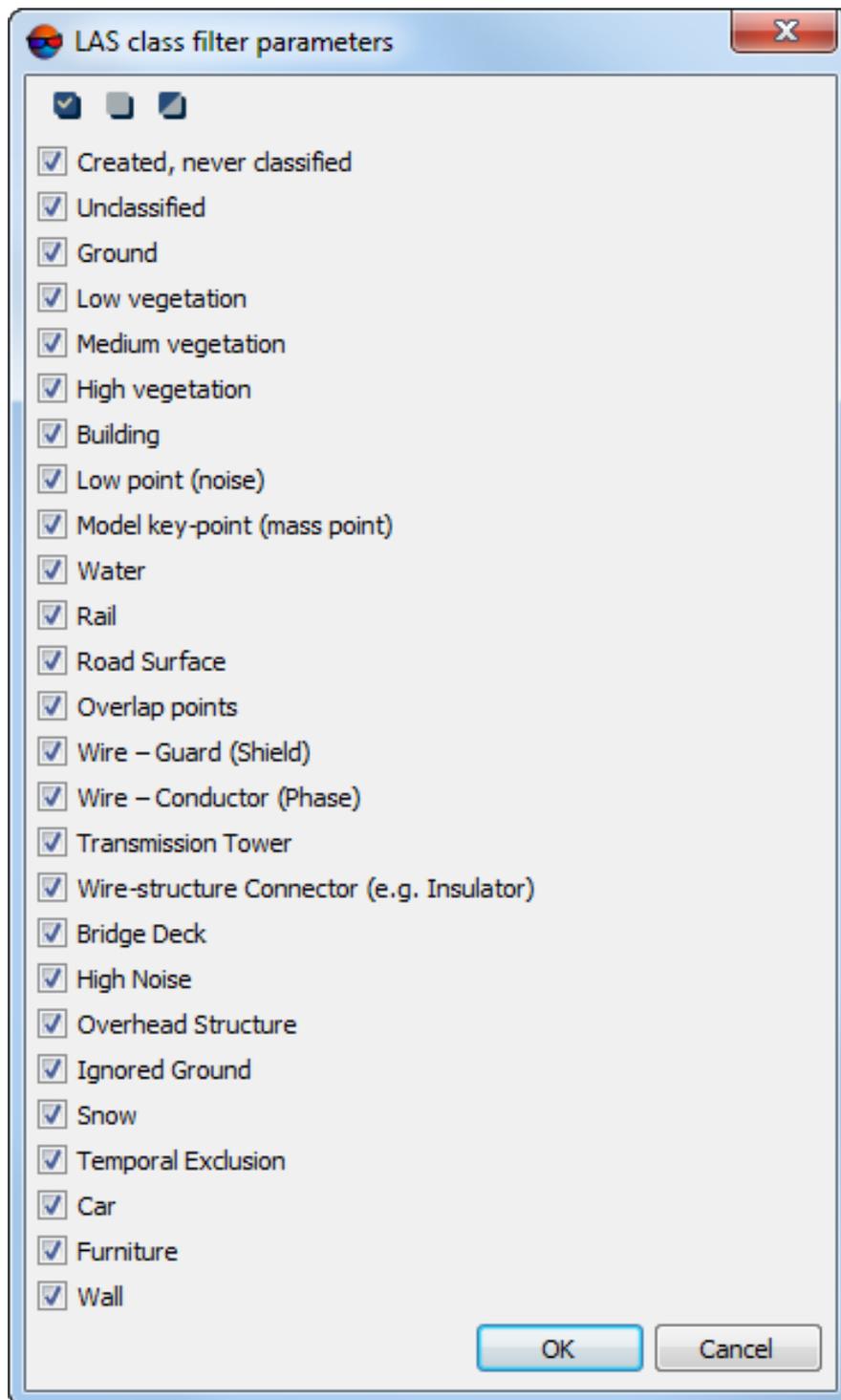


Fig. 13. The LAS classification filter parameters window

To exclude LAS points ranked in a certain way from the DEM creation process, clear the appropriate checkboxes. For group selection of point classes, the following buttons are provided in the **LAS classification filter parameters** window:

-  – allows user to select all the classes of lidar points;
-  – allows user to deselect all classes of lidar points;
-  – allows user to invert selection of point classes.



Excluding certain groups of points from the process of DEM creation can lead to the appearance of so-called “gaps” (see “Null cells in DEM” in the “[DTM Generation](#)” User Manual).

It should be noted that the generation of null cells in a DEM depends both on the characteristics of the source data (point cloud density, certain groups of points excluded from processing) and the entered parameters for DEM construction, such as **DEM cell size**, interpolation, and a specified **interpolation radius**.

7. Click OK. The process of DEM building starts. The created DEM is saved in the specified file when the process completes.

To use distributed computing for point cloud conversion, do the following:

1. Change settings and run the distributed processing server/client (see the “Distributed processing” chapter in the “[General information about system](#)” User Manual).
2. Click the **Distributed processing** button. Distributed processing tasks are created.

4.2.2. Convert LAS to DEM (from active profile resources)

The system allows to convert LIDAR data to DEM for the further usage in the *PHOTOMOD* system.

For DEM building perform the following actions:

1. Choose **Terrain** › **LAS** › **Convert LAS to DEM**. The **Convert LAS to DEM** window opens:

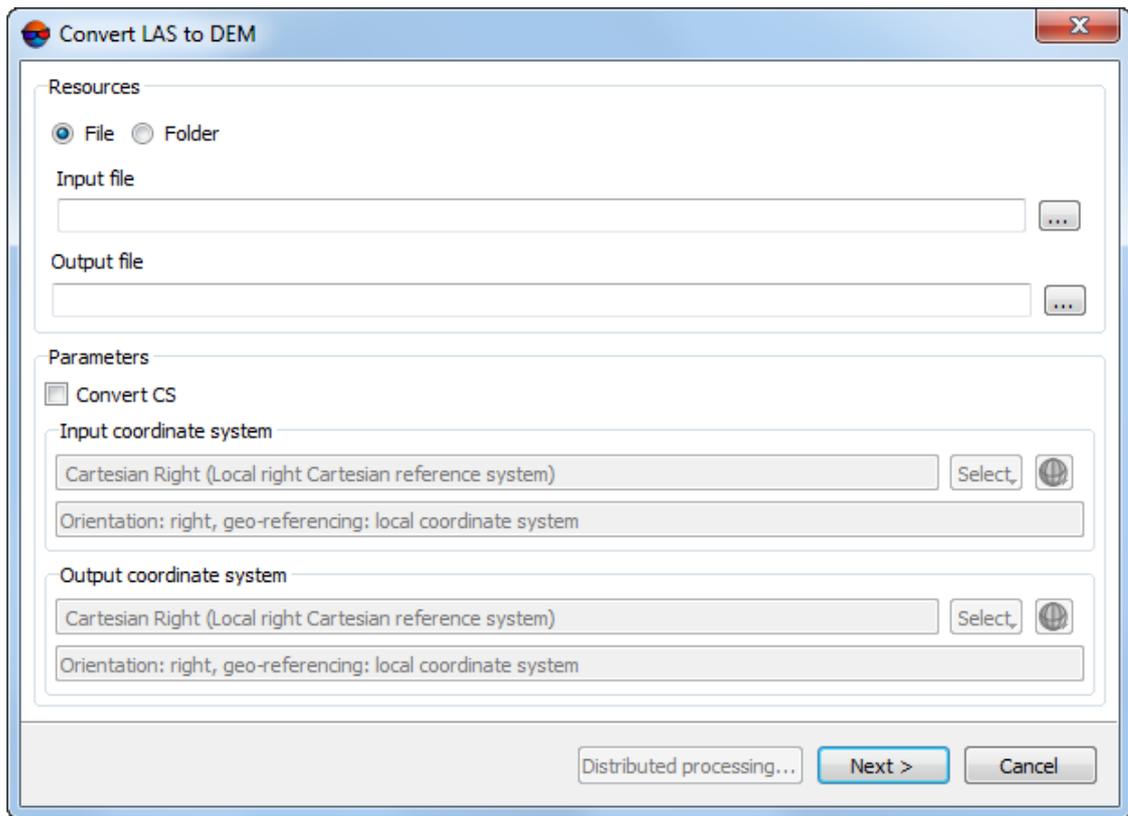


Fig. 14. The Convert LAS to DEM window

2. Select the input **Resources**:
 - [optional] **File** – to process a point cloud saved as a single file;
 - [optional] **Folder** – to process a fragmented point cloud.
3. Click the **...** button to specify a path to the source data;
4. Click the **...** button to specify target folder for output LAS-file(s) in active profile resources;
5. [optional] to change points cloud coordinate system, perform the following actions:
 - In the **Input coordinates system** section select actual Coordinate system of point cloud. Perform the following actions to do this:
 1. Click the **Select...** button to specify initial coordinate system.

Coordinate system is specified using one of the following ways:

 - **From DB** – from international or Russian coordinate system database (see “Coordinate systems databases” in the “[Project creation](#)” User Manual);

- **From file** – allows to select coordinate system from files with *.x-ref-system, extension located out of active profile resources;
- **From resource** – from files with *.x-ref-system extension located in active profile resources, for example, to select coordinate system from another active profile project.
- **From GeoCalculator** – from the list of *GeoCalculator* program database (see the “Coordinate Systems” chapter in “[The GeoCalculator program](#)” User manual).



The *GeoCalculator* program allows to edit coordinate systems, to create new ones, to perform import and export of coordinate systems (see the “[The GeoCalculator program](#)” User Manual).



The system also allows to select coordinate system from a list of recently used coordinate systems.

2. [optional] When choosing coordinate system from database the **Coordinate system database** opens, which contains the list of coordinate systems.



To perform fast search for coordinate system, input the whole coordinate system name or its part to the **Find** input field.

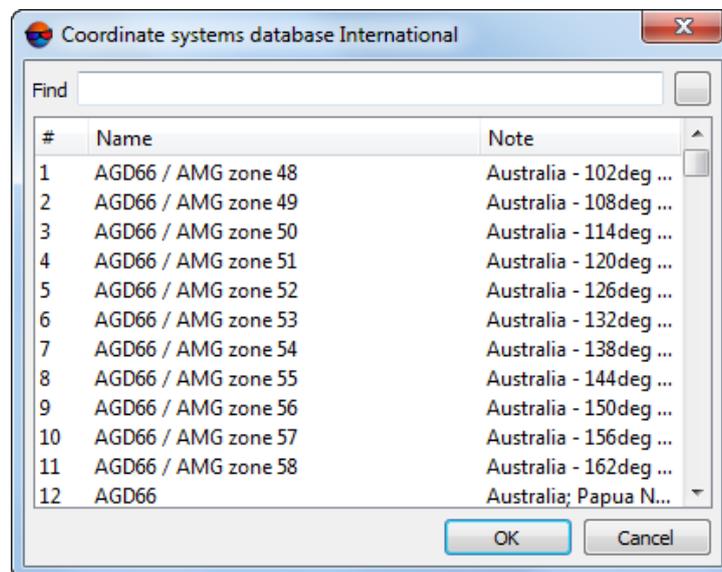


Fig. 15. Window used to select coordinate system from coordinate system database

3. [optional] To choose geoid to be used, click the  button. Select proper type of geoid usage:
 - **No geoid**;

o **EGM 96.**



The system allows to use the **EGM2008** geoid. See more details in the [Installation EGM2008 Geoid User Manual](#). After installation the geoid is displayed in the list.



PHOTOMOD GeoCalculator provides for creating a user height system (geoid) with preset parameters. *PHOTOMOD* system allows to use previously created custom vertical datum (geoid). See instructions in the “Creating custom height system” chapter of “[The GeoCalculator program](#)” User Manual.

- In the **Output coordinate system** define target coordinate system in which it is necessary to convert the point cloud. To do this perform actions from step 5.
6. Click **Next**. **Estimated DEM size, width, height, and boundaries** will be calculated in the **Convert LAS to DEM** window:

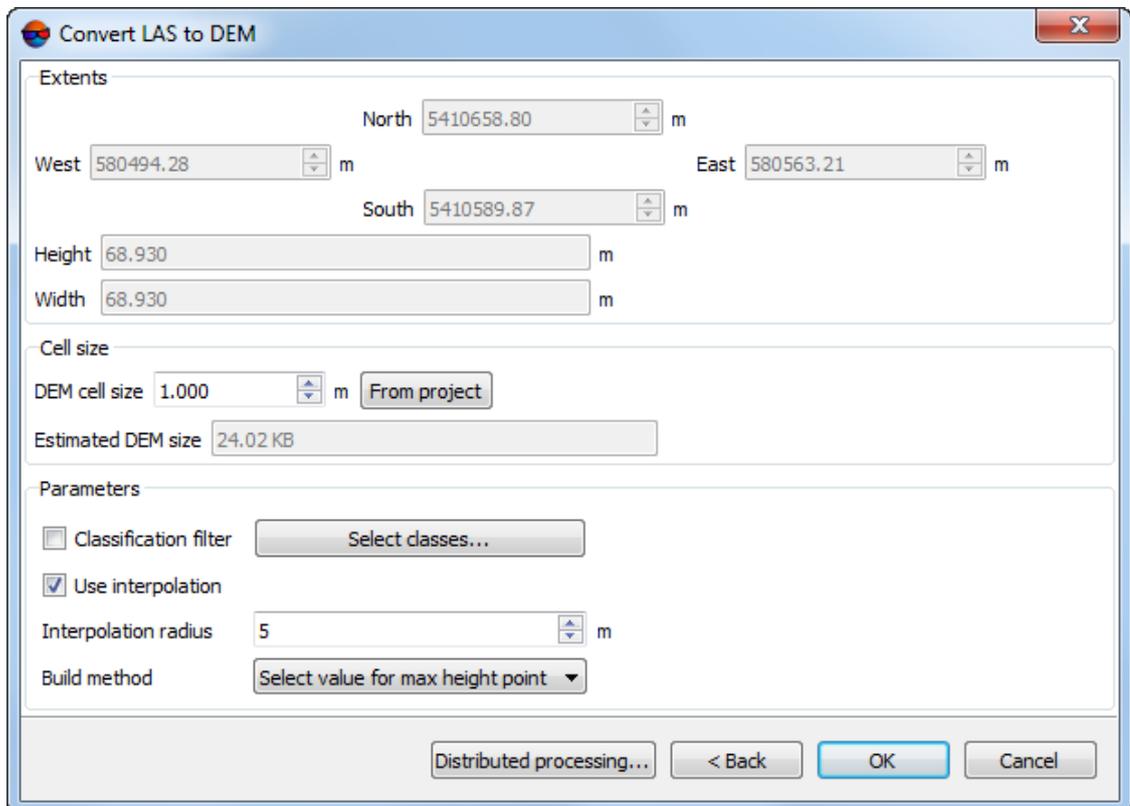


Fig. 16. The Convert LAS to DEM window

7. Specify the **DEM cell size** in meters. Automatic recalculation of the **Estimated DEM size** is performed while change the **DEM cell size**;
8. Set the DEM building **parameters**:
 - To **use interpolation** set an appropriate checkbox and specify the **interpolation radius** in project units;
 - Select the **build method**:
 - **Average**;
 - **Select value from max height point**;
 - **Select max weight point**;
 - **Select point with max quality**.
9. [optional] set the **Classification filter** checkbox to set LAS preliminary filtering parameters according to the classification of points (see the LAS [specification](#) published by *ASPRS* and [Appendix A](#));

Click **Select classes**. The **LAS classification filter parameters** window opens:

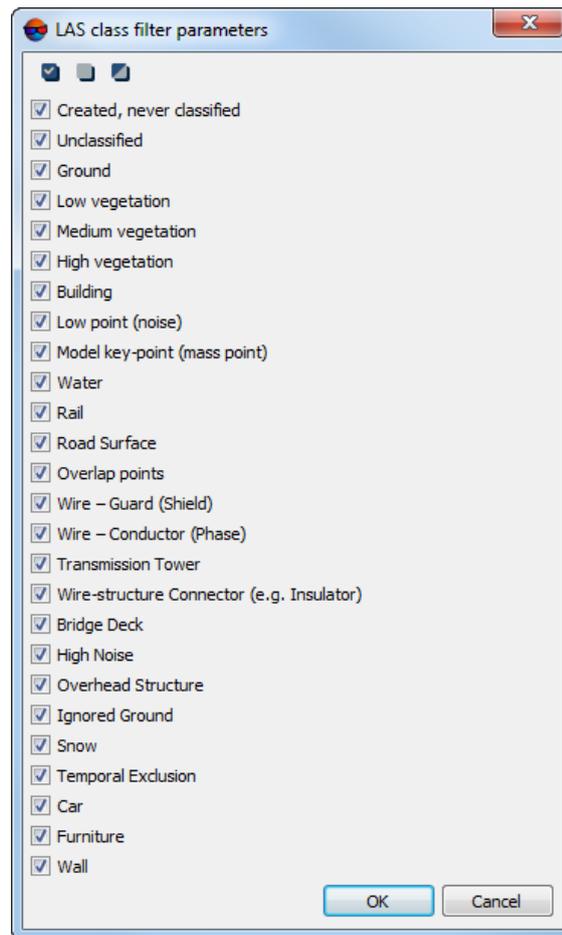


Fig. 17. The LAS classification filter parameters window

To exclude LAS points ranked in a certain way from the DEM creation process, clear the appropriate checkboxes. For group selection of point classes, the following buttons are provided in the **LAS classification filter parameters** window:

-  – allows user to select all the classes of lidar points;
-  – allows user to deselect all classes of lidar points;
-  – allows user to invert selection of point classes.



Excluding certain groups of points from the process of DEM creation can lead to the appearance of so-called “gaps” (see “Null cells in DEM” in the “[DTM Generation](#)” User Manual).

It should be noted that the generation of null cells in a DEM depends both on the characteristics of the source data (point cloud density, certain groups of points excluded from processing) and the entered parameters for DEM construction, such as **DEM cell size**, interpolation, and a specified **interpolation radius**.

10. Click OK to start conversion.

To use distributed computing for point cloud conversion, do the following:

1. Change settings and run the distributed processing server/client (see the “Distributed processing” chapter in the “[General information about system](#)” User Manual).
 2. Click the **Distributed processing** button. Distributed processing tasks are created.
11. The created DEM is opened in 2D-window when the process completes.

4.2.3. True Ortho creation

The system allows to convert LIDAR data to True Ortho for the further usage in the PHOTOMOD system.

For True Ortho building perform the following actions:

1. Choose **Terrain > LAS > Convert LAS to True Ortho**. The **Convert LAS to True Ortho** window opens:

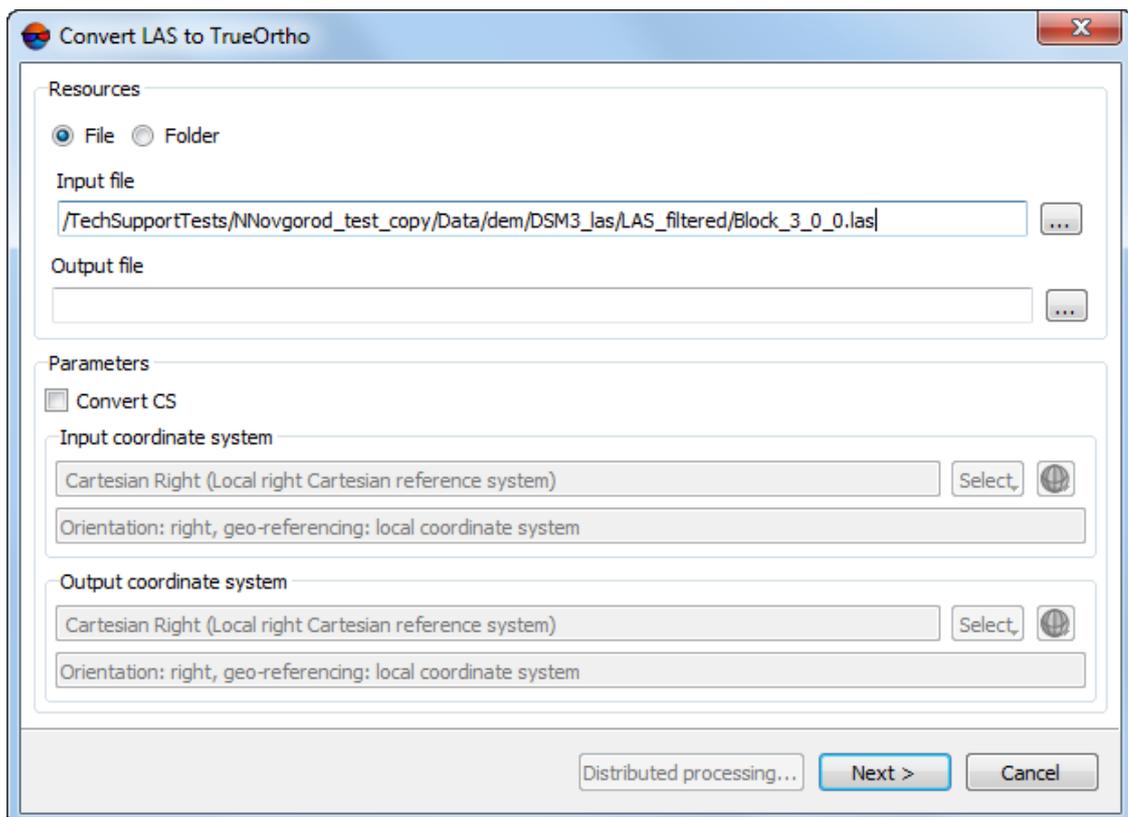


Fig. 18. The Convert LAS to True Ortho window

2. Select the input **Resources**:

- [optional] **File** – to process a point cloud saved as a single file;
- [optional] **Folder** – to process a fragmented point cloud.

3. Click the  button to specify a path to the source data;

4. Click the  button to specify target folder for output LAS-file(s) in active profile resources;

5. [optional] to change points cloud coordinate system, perform the following actions:

- In the **Input coordinates system** section select actual Coordinate system of point cloud. Perform the following actions to do this:

1. Click the **Select...** button to specify initial coordinate system.

Coordinate system is specified using one of the following ways:

- **From DB** – from international or Russian coordinate system database (see “Coordinate systems databases” in the “[Project creation](#)” User Manual);
- **From file** – allows to select coordinate system from files with *.x-ref-system, extension located out of active profile resources;
- **From resource** – from files with *.x-ref-system extension located in active profile resources, for example, to select coordinate system from another active profile project.
- **From GeoCalculator** – from the list of *GeoCalculator* program database (see the “Coordinate Systems” chapter in “[The GeoCalculator program](#)” User manual).



The *GeoCalculator* program allows to edit coordinate systems, to create new ones, to perform import and export of coordinate systems (see the “[The GeoCalculator program](#)” User Manual).



The system also allows to select coordinate system from a list of recently used coordinate systems.

2. [optional] When choosing coordinate system from database the **Coordinate system database** opens, which contains the list of coordinate systems.



To perform fast search for coordinate system, input the whole coordinate system name or its part to the **Find** input field.

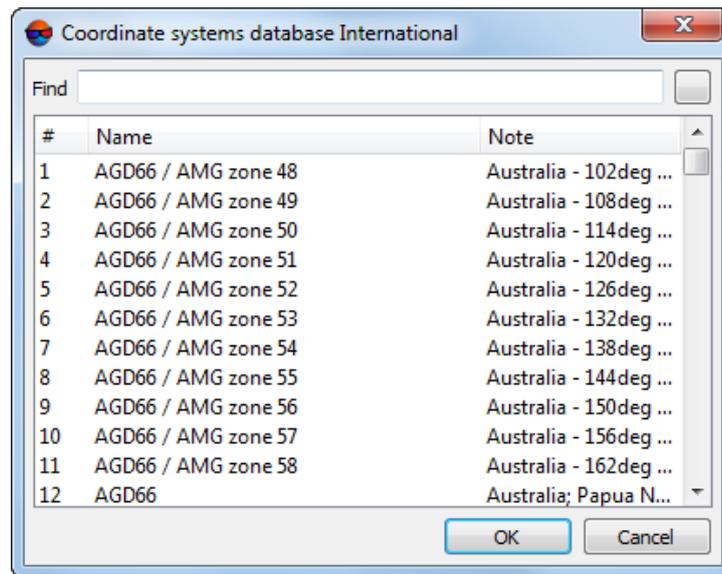


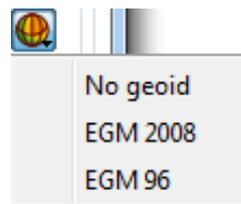
Fig. 19. Window used to select coordinate system from coordinate system database

3. [optional] To choose geoid to be used, click the  button. Select proper type of geoid usage:

- **No geoid;**
- **EGM 96.**



The system allows to use the **EGM2008** geoid. See more details in the [Installation EGM2008 Geoid User Manual](#). After installation the geoid is displayed in the list.



PHOTOMOD GeoCalculator provides for creating a user height system (geoid) with preset parameters. *PHOTOMOD* system allows to use previously created custom vertical datum (geoid). See instructions in the “Creating custom height system” chapter of “[The GeoCalculator program](#)” User Manual.

- In the **Output coordinate system** define target coordinate system in which it is necessary to convert the point cloud. To do this perform actions from step 5.
6. Click **Next**. **Estimated true ortho size, width, height, and boundaries** will be calculated in the **Convert LAS to true ortho** window:

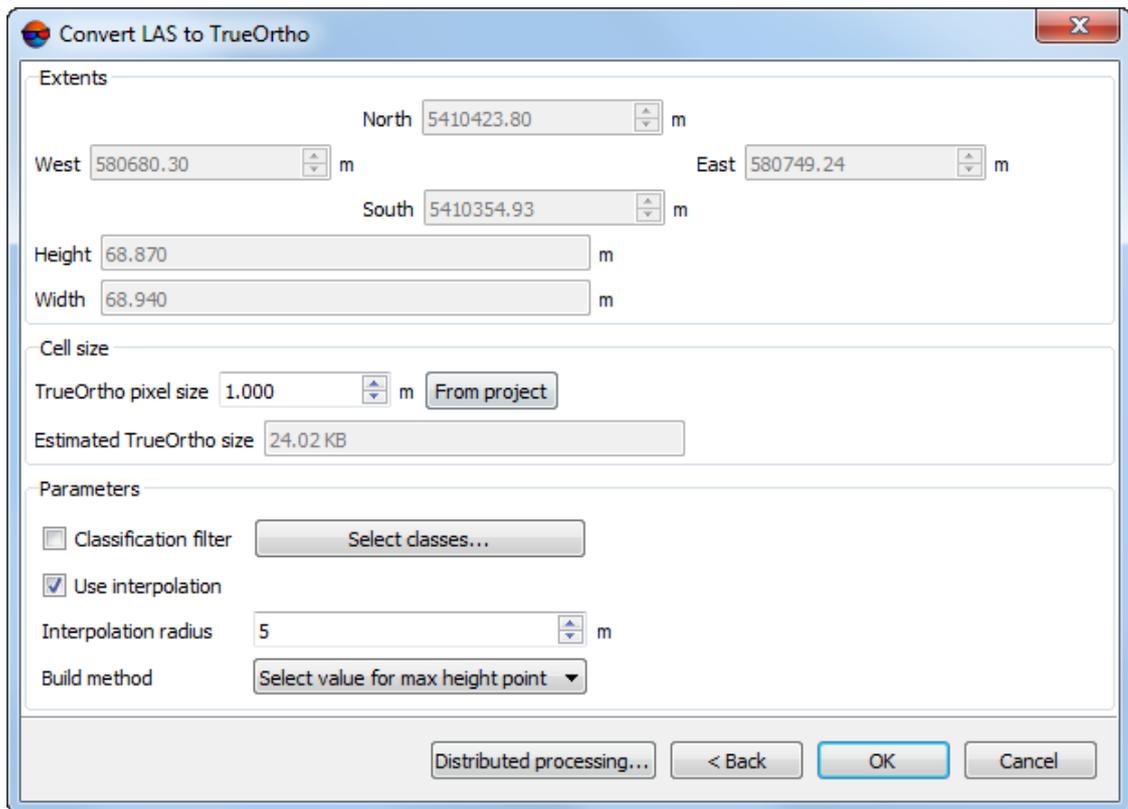


Fig. 20. The Convert LAS to True Ortho window

7. Specify the **true ortho pixel size** in meters. Automatic recalculation of the **Estimated true ortho size** is performed while change the **true ortho cell size**;
8. Set the true ortho building **parameters**:
 - [optional] set the **Classification filter** checkbox to set LAS preliminary filtering parameters according to the classification of points (see the LAS [specification](#) published by *ASPRS* and [Appendix A](#));

Click **Select classes**. The **LAS classification filter parameters** window opens:

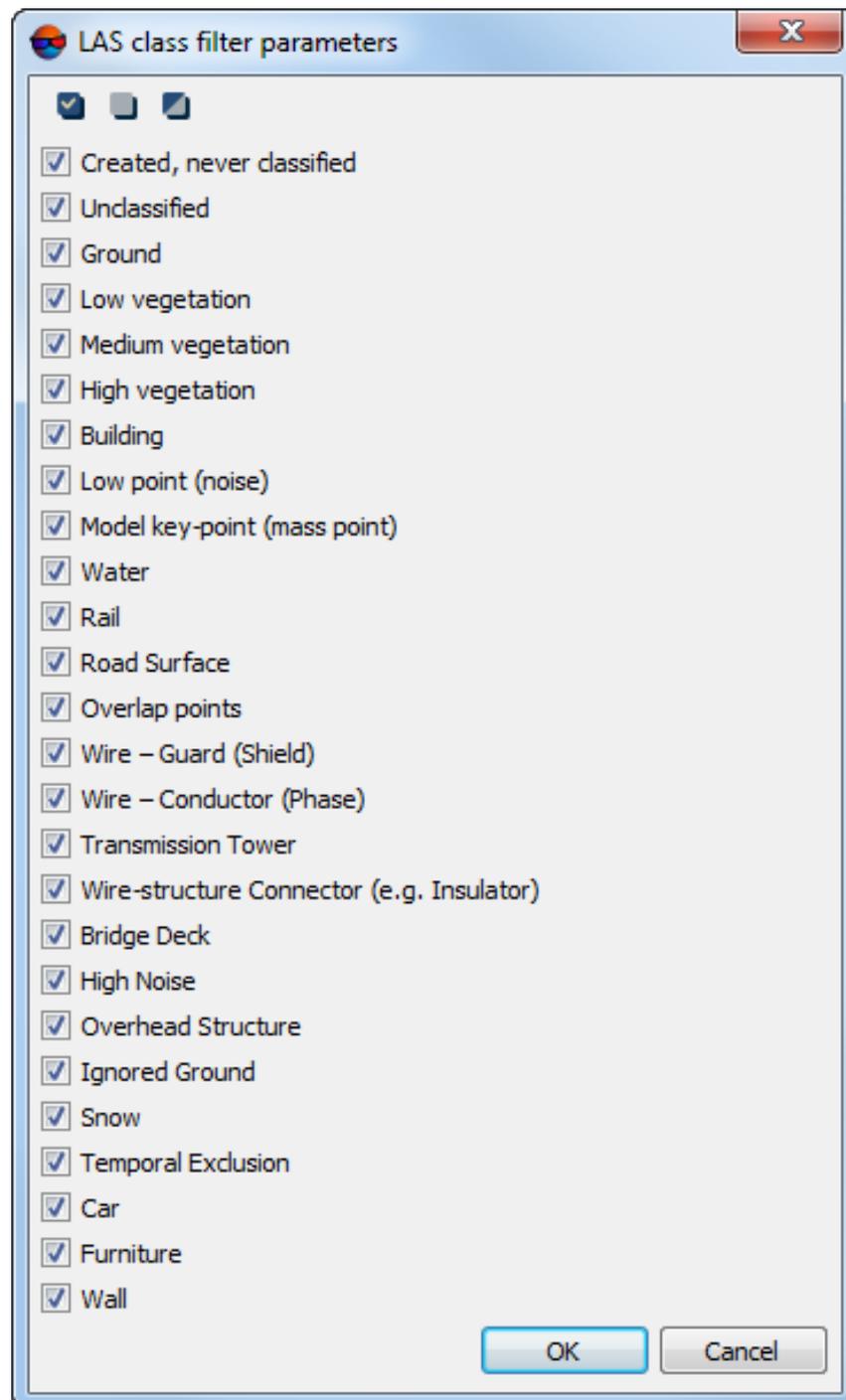


Fig. 21. The LAS classification filter parameters window

To exclude LAS points ranked in a certain way from the true ortho creation process, clear the appropriate checkboxes. For group selection of point classes, the following buttons are provided in the **LAS classification filter parameters** window:

- – allows user to select all the classes of lidar points;

-  – allows user to deselect all classes of lidar points;
-  – allows user to invert selection of point classes.



Excluding certain groups of points from the process of true ortho creation can lead to the appearance of so-called “gaps”.

- To **use interpolation** set an appropriate checkbox and specify the **interpolation radius** in project units;
 - Select the **build method**:
 - **Average**;
 - **Select value from max height point**;
 - **Select max weight point**;
 - **Select point with max quality**.
9. Click OK to start conversion. To use distributed computing for point cloud conversion, do the following:
1. Change settings and run the distributed processing server/client (see the “Distributed processing” chapter in the “[General information about system](#)” User Manual).
 2. Click the **Distributed processing** button. Distributed processing tasks are created.
10. The created true ortho is opened in 2D-window when the process completes.

To convert all point clouds opened in **Load LAS** window into single orthoimage – click the  button of main **Load LAS** window toolbar and specify the parameters described above.



Point clouds will be transformed into a single orthophotomap. Only the clouds displayed in the workspace in the right part of the **Load LAS** window will be transformed



To display any given point cloud in the **Load LAS** workspace, set the appropriate checkbox in the list of loaded LAS files.



Coordinate system change is not available in the case of rapid transform of LAS files started from the toolbar of the **Load LAS** window.

4.2.4. Transformation of point cloud coordinate system

The system provides opportunity to transform LAS-files from one coordinate system to another.

In order to transform LAS-files to another coordinate system perform the following actions:

1. Select **Terrain > LAS > Transform LAS coordinates**. The **Transform LAS coordinates** window opens.

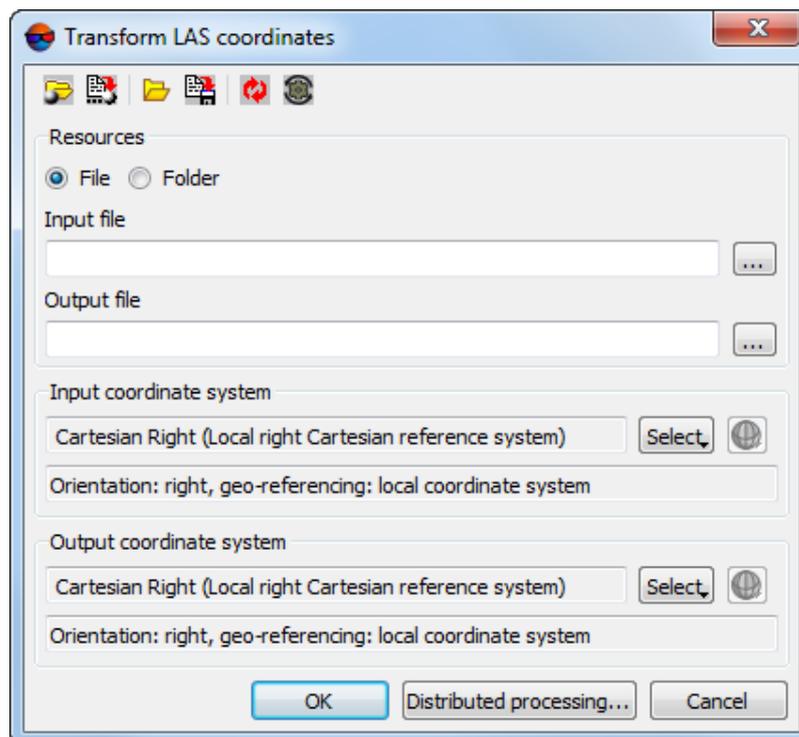


Fig. 22. Transform LAS to another coordinate system

A toolbar in the upper part of the window is intended to save/load parameter's settings and contains the following buttons:

-  – allows to load parameter's settings saved previously to active profile resources;
-  – allows to save all parameter's settings to *.x-ini file located in active profile resources;
-  – allows to load parameter's settings from *.x-ini file located in a folder of Windows file system;

-  – allows to save parameter's settings to *.x-ini file located in a folder of Windows file system;
 -  – allows to restore the last-session's settings;
 -  – allows to restore default parameter's settings.
2. Select the input **Resources**:
 - [optional] **File** – to process a point cloud saved as a single file;
 - [optional] **Folder** – to process a fragmented point cloud.
 3. Click the  button to specify a path to the source data;
 4. Click the  button to specify target folder for output LAS-file(s) in active profile resources;
 5. In the **Input coordinates system** section select actual Coordinate system of point cloud. Perform the following actions to do this:

1. Click the **Select...** button to specify initial coordinate system.

Coordinate system is specified using one of the following ways:

- **From DB** – from international or Russian coordinate system database (see “Coordinate systems databases” in the “[Project creation](#)” User Manual);
- **From file** – allows to select coordinate system from files with *.x-ref-system, extension located out of active profile resources;
- **From resource** – from files with *.x-ref-system extension located in active profile resources, for example, to select coordinate system from another active profile project.
- **From GeoCalculator** – from the list of *GeoCalculator* program database (see the “Coordinate Systems” chapter in “[The GeoCalculator program](#)” User manual).



The *GeoCalculator* program allows to edit coordinate systems, to create new ones, to perform import and export of coordinate systems (see the “[The GeoCalculator program](#)” User Manual).



The system also allows to select coordinate system from a list of recently used coordinate systems.

2. [optional] When choosing coordinate system from database the **Coordinate system database** opens, which contains the list of coordinate systems.



To perform fast search for coordinate system, input the whole coordinate system name or its part to the **Find** input field.

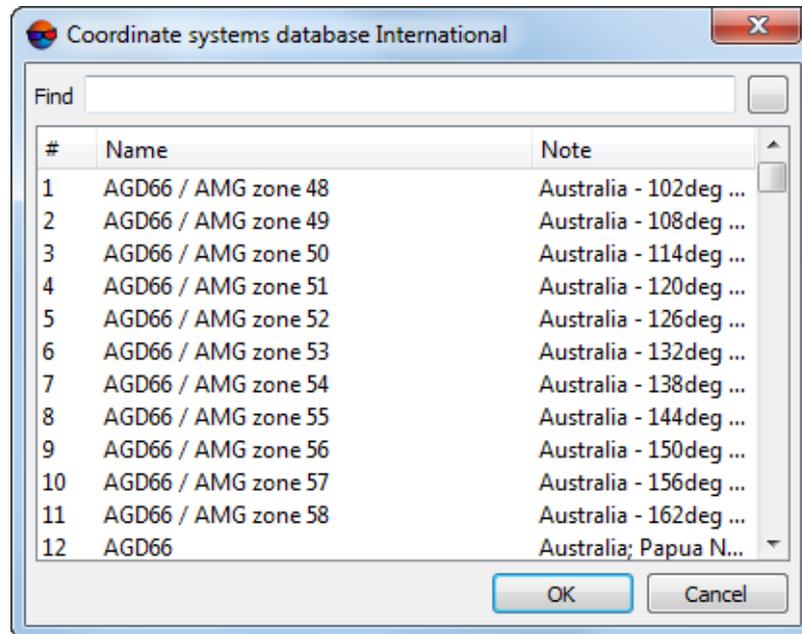


Fig. 23. Window used to select coordinate system from coordinate system database

3. [optional] To choose geoid to be used, click the  button. Select proper type of geoid usage:

- **No geoid;**
- **EGM 96.**



The system allows to use the **EGM2008** geoid. See more details in the [Installation EGM2008 Geoid User Manual](#). After installation the geoid is displayed in the list.



PHOTOMOD GeoCalculator provides for creating a user height system (geoid) with preset parameters. *PHOTOMOD* system allows to use previously created custom vertical datum (geoid). See instructions in the “Creating custom height system” chapter of “[The GeoCalculator program](#)” User Manual.

6. In the **Output coordinate system** define target coordinate system in which it is necessary to convert the point cloud. To do this perform actions from step 5.

7. Click OK to start converting point cloud coordinate system.

To use distributed computing for changing of point cloud coordinate system, do the following:

1. Change settings and run the distributed processing server/client (see the “Distributed processing” chapter in the “[General information about system](#)” User Manual).
2. Click the **Distributed processing** button. Distributed processing tasks are created. Number of created tasks matches with number of LAS-files.

4.3. Data compression

To save free hard disk space, the system provides for compressing LAS-files into archives with the *.laz extension. To provide for further work with LAS-files, the system also allows to extract archives with the *.laz extension.

To create an archive file with the *.laz extension, perform the following:

1. Choose **Terrain > LAS > Convert LAS-files to LAZ...** The **Convert LAS-files to LAZ** window opens:

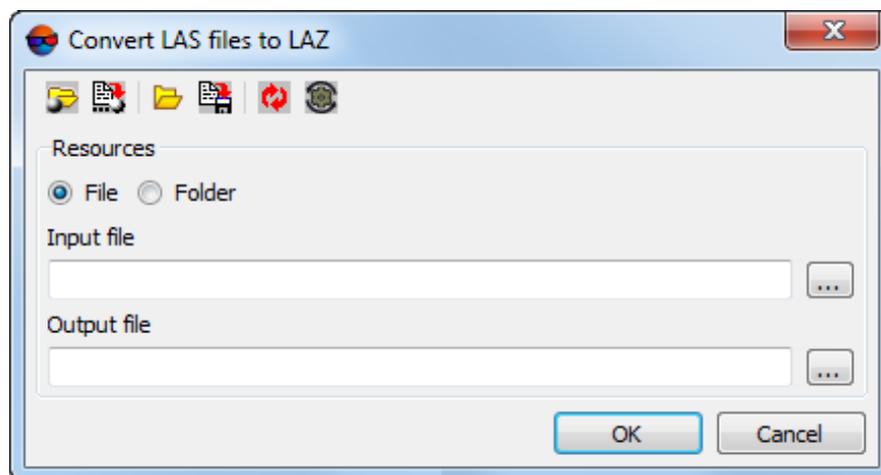


Fig. 24. The Convert LAS-files to LAZ window

A toolbar in the upper part of the window is intended to save/load parameter’s settings and contains the following buttons:

-  – allows to load parameter’s settings saved previously to active profile resources;
-  – allows to save all parameter’s settings to *.x-ini file located in active profile resources;

-  – allows to load parameter's settings from *.x-ini file located in a folder of Windows file system;
 -  – allows to save parameter's settings to *.x-ini file located in a folder of Windows file system;
 -  – allows to restore the last-session's settings;
 -  – allows to restore default parameter's settings.
2. Select the input **Resources**:
 - [optional] **File** – to process a point cloud saved as a single file;
 - [optional] **Folder** – to process a fragmented point cloud.
 3. Click the  button to specify a path to the source data;
 4. Click the  button to specify target folder for output LAS-file(s) in active profile resources;
 5. Click OK.

To extract an archive with the *.laz extension, perform the following:

1. Choose **Terrain > LAS > Convert LAZ-files to LAS....** The **Convert LAZ-files to LAS** window opens:

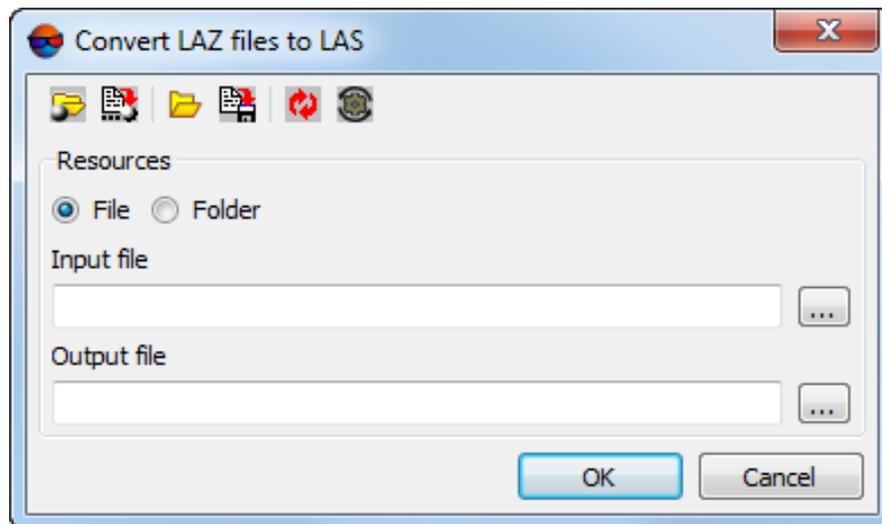


Fig. 25. The Convert LAZ-files to LAS window

A toolbar in the upper part of the window is intended to save/load parameter's settings and contains the following buttons:

-  – allows to load parameter's settings saved previously to active profile resources;
 -  – allows to save all parameter's settings to *.x-ini file located in active profile resources;
 -  – allows to load parameter's settings from *.x-ini file located in a folder of Windows file system;
 -  – allows to save parameter's settings to *.x-ini file located in a folder of Windows file system;
 -  – allows to restore the last-session's settings;
 -  – allows to restore default parameter's settings.
2. Select the input **Resources**:
 - [optional] **File** – to process a point cloud saved as a single file;
 - [optional] **Folder** – to process a fragmented point cloud.
 3. Click the  button to specify a path to the source data;
 4. Click the  button to specify target folder for output LAS-file(s) in active profile resources;
 5. Click OK.

4.4. LAS interpolation

The system allows to change the resolution and size of LAS point cloud fragments (tiles).

To do this, perform the following:

1. Choose **Terrain > LAS > LAS Interpolation....** The **LAS interpolation** window opens;

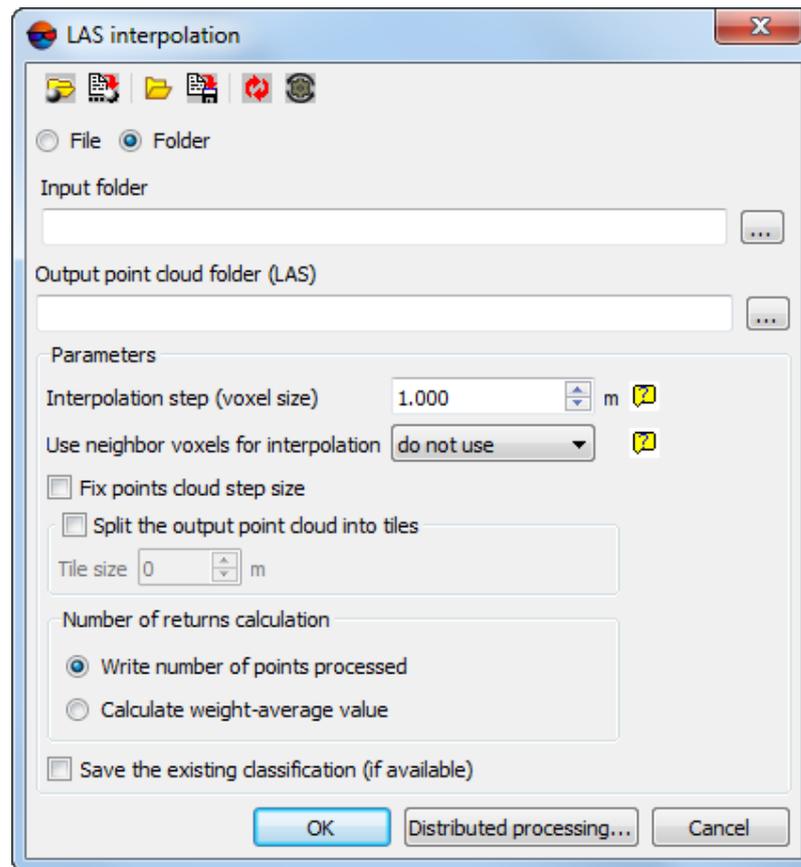


Fig. 26. The LAS interpolation window

The **LAS interpolation** window contains the following elements:

- A toolbar in the upper part of the window, which is intended to save/load parameter's settings and contains the following buttons:
 -  – allows to load parameter's settings saved previously to active profile resources;
 -  – allows to save all parameter's settings to *.x-ini file located in active profile resources;
 -  – allows to load parameter's settings from *.x-ini file located in a folder of Windows file system;
 -  – allows to save parameter's settings to *.x-ini file located in a folder of Windows file system;
 -  – allows to restore the last-session's settings;
 -  – allows to restore default parameter's settings.

- The interpolation **Parameters** section.
2. Select the input resources:
 - [optional] **File** – to process a point cloud saved as a single file;
 - [optional] **Folder** – to process a fragmented point cloud.
 3. Click the button to specify a path to the source data;
 4. Click the button to specify target folder for output LAS-file(s) in active profile resources;
 5. Set the following LAS interpolation **parameters** in the appropriate section:
 - **Interpolation step** (a voxel size) – the output cloud point resolution, in the project units;



A volumetric pixel (*voxel*) is the three-dimensional equivalent of a pixel and the tiniest distinguishable element of a 3D object. Volume pixels are used like building blocks to form a larger 3D object.

In this case, a *voxel* is a small fragment of the input point cloud, within which, during interpolation, one point of the output cloud is calculated. Not to be confused with the tile size.

- **Use neighbor voxels for interpolation** – allows to take into account the content of neighbor voxels (see the figure below) when a current voxel processing:
 - **do not use** – neighbor voxels are not taken into account during the interpolation of a processed voxel content (a voxel is processed separately from others);
 - **use 6 neighbors** – when interpolating the content of the processed voxel of a point cloud, points located in the 6 closest voxels are taken into account;
 - **use 18 neighbors** – when interpolating the content of the processed voxel of a point cloud, points located in the 18 closest voxels are taken into account;
 - **use 26 neighbors** – when interpolating the content of the processed voxel of a point cloud, points located in the 26 closest voxels are taken into account.

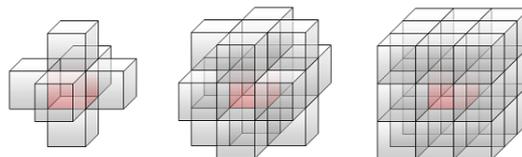


Fig. 27. A processed voxel of a point cloud (red) and the closest neighbor voxels (6, 18 or 26)

- The **Fix points cloud step size** checkbox allows to place each point of an output cloud exactly in the center of the voxel within which this point was calculated. Otherwise – the location of the given point is determined from the interpolation of an input cloud's points within a voxel.
- To **split output point cloud into tiles** set the appropriate checkbox and specify **the tile size** of an output point cloud (XYZ), in the project units;



Use this function carefully. When creating an output point cloud as a single file it is necessary to take into account the size of the output cloud size and the system performance.

Creation of more than 4 – 8 Gb files may negatively affect the system performance and impede viewing and/or further processing the output point cloud.

The size of the output file can be assessed as follows: if the initial point cloud is fragmented, the size of the output LAS as a single file is approximately corresponds to the amount of space on the workstation hard drive, which is the **Input point cloud folder** occupies.

- The **number of returns calculation** section allows to set the algorithm to calculate the number of reflected pulses for the output LAS points:
 - **calculate the weight-average value** of the number of reflected pulses for the each point of output LAS, taking into account this parameter value for the processed input cloud points;
 - **record the number of points involved** in the processing when calculating the output LAS point.



The system supports the use of LAS files regardless of the way the data was received.

Thus, the system allows to interpolate both lidar data themselves and LAS point clouds created using *PHOTOMOD* (see the “Dense DEM generation using SGM method” section of the “[DTM Generation](#)” User Manual).

Hence, the “number of reflected pulses” parameter for the input LAS points may have different meanings, depending on the source of the given point cloud.

In case of the cloud of points, created during the DEM creation using the SGM method, the number of reflected pulses in the given point is the number of stereopairs on the basis of which a particular point was calculated: 1, 2, 3, 4, 5, 6, 7, or 8.

Limitation of the “number of reflected pulses” by 1 to 8 results from the limitations of the LAS format itself, accordingly, in the latter case, the number of stereopairs can be both “8” and “8 and more”.

For points of the output LAS point cloud after interpolation, the meaning and values of the “number of reflected pulses” parameter depends on the input data and on whether the **Calculate numbers of returns as weighted average** checkbox was set or cleared.

- To **save the existing classification (if available)** set the appropriate checkbox.

6. Click OK to start LAS interpolation in usual mode.

In order to interpolate LAS points cloud using distributed processing, do the following:

1. Change settings and run the distributed processing server/client (see the “Distributed processing” chapter in the “General information about system” User Manual).
2. Click the **Distributed processing** button.

4.5. Point cloud colorization by project images

The system provides for colorizing a point cloud using project images. This function is available for any point cloud that displays objects within a territory covered by the project images. When coloring, initial points of the LAS file are sequentially projected onto each image of the project.

To do this, perform the following actions:

1. Load the required project;
2. Choose **Terrain > LAS > Colorization by project images**. The **Colorization by project images** window opens;

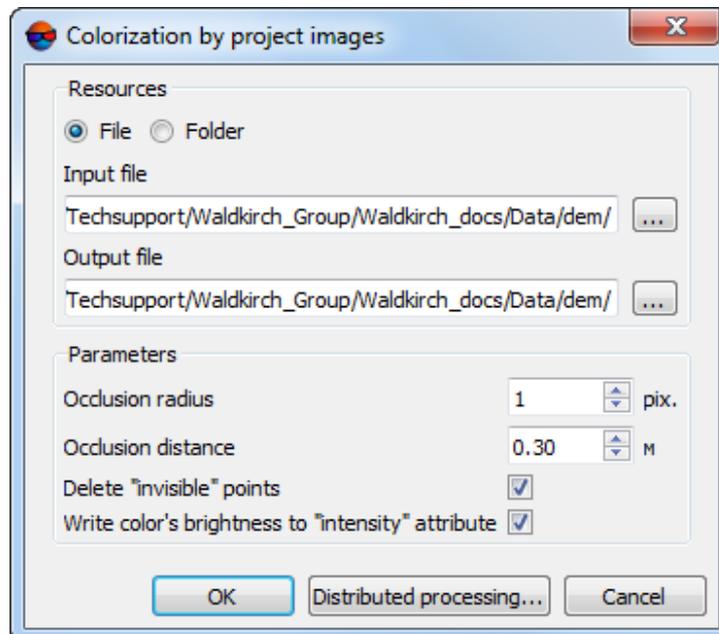


Fig. 28. The Colorization by project images window

3. Select the input **Resources**:

- [optional] **File** – to process a point cloud saved as a single file;
 - [optional] **Folder** – to process a fragmented point cloud.
4. Click the button to specify a path to the source data;
 5. Click the button to specify target folder for output LAS-file(s) in active profile resources;
 6. Set the overlapping objects colorization **parameters**:
 - Set the **occlusion radius** around the pixel preselected for LAS point coloring (for each image of the project the given point was projected onto), in pixels;
 - Set the **Occlusion distance**, in the project units.

If within the **occlusion radius** neighbor pixels are found that are closer to the LAS point, and the difference in distance from pixels to the point exceeds **occlusion distance**, the pixel of the given image will not be involved in final LAS point color determination.



Recommended **Occlusion radius** is several pixels. If this parameter is set to zero, invisible areas will not be checked what may result in incorrect colorization of overlapping objects (especially when processing projects with “oblique” survey data as source data).

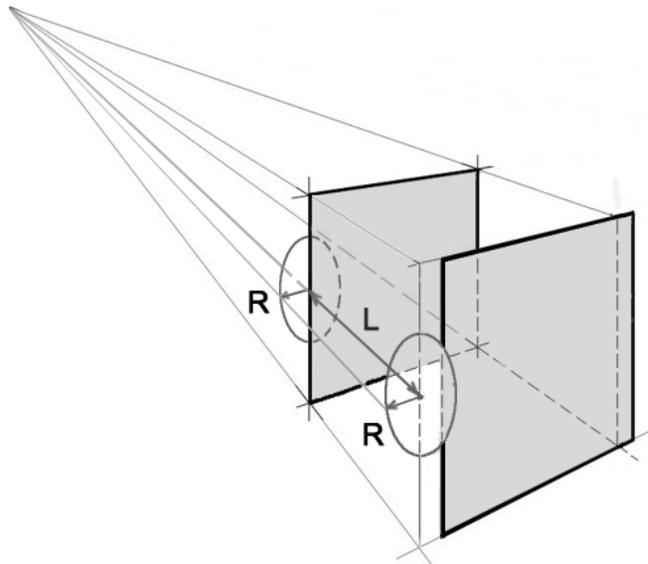


Fig. 29. Invisible areas when texturing overlapping objects (hatched), where R is the **Occlusion radius** and L is the **Occlusion distance**

7. [optional] to **delete “invisible” points**, that could not be colored, set the appropriate checkbox;
8. [optional] to **write color’s brightness to “intensity” attribute** of the point, set the appropriate checkbox (see [Section 3.1](#));



Initially, for a point cloud obtained as a result of laser scanning, this attribute contains a value describing the power of the reflected laser pulse.

For a so-called “photogrammetric” point cloud (e.g., *PHOTOMOD*-created), the intensity means the value of the color brightness for the given point.

Accordingly, if colorization is performed for a “photogrammetric” point cloud, then, if the checkbox is set, this value will just be overwritten.

9. Click OK. As a result, processed LAS files will be created in the output folder having the names identical to the file names in the input folder.

In order to perform the LAS files colorization using distributed processing, do the following:

1. Change settings and run the distributed processing server/client (see the “Distributed processing” chapter in the “[General information about system](#)” User Manual).
2. Click the **Distributed processing** button.

4.6. Lidar point classification

The system provides for attributing [classes](#) to lidar points (or changing them). The following lidar point classification procedure is recommended (generally):

- [Automatic](#) lidar point classification;
- Viewing and analyzing the results in the **Load LAS** window;



Click the  button to enable the coloring mode to accordance with objects classification.

- [Manual classification](#) of individual groups of points.



Viewing and manual processing of a point cloud of large size may require the use of significant system resources. The placement of processed files on a SSD drive, as well as the [correct dividing of a single point cloud file into separate fragments](#) (tiles) can contribute to an increase in system performance.



The system also provides for point cloud classification using neural network algorithms, if this cloud contains the information on [point colors](#) (see the “[Neural processing of LIDAR data](#)”

User Manual). A special task-oriented module designed to operate together with *PHOTOMOD* is to be installed separately for this purpose.

PHOTOMOD version and build numbers must match the neural processing module number exactly. Before the neural processing module installation, automatic search for the folder where *PHOTOMOD* is installed is carried out, as well as the interoperability check.

4.6.1. Automatic classification by NDVI

The system provides for performing the points classification through the computation of NDVI of processed points.



NDVI is the normalized difference vegetation index. *Vegetation index* is a numerical indicator of the quality and quantity of vegetation in the studied area.

NDVI is one of the most widely used vegetation indices. It is the ratio between the difference in the intensities of reflected light in the red (Red) and near infrared (NIR) bands and their sum:

$$NDVI = (NIR - RED) / (NIR + RED)$$



To calculate the *NDVI* index, the input lidar data must have an IR channel. The IR band is supported e.g. for some data record formats in v1.4 LAS files (Point Data Record Format 8). Format and version of initial LAS-files depend on data provider. More info see *ASPRS (American Society for Photogrammetry and Remote Sensing) v1.4 LAS specifications*.



The system also provides for classification in project images using the *NDVI* index (if the source images have an IR channel). To do this, create a point cloud using the functionality of the *PHOTOMOD* software first (see the “Dense DEM generation using SGM method” chapter of “[DTM Generation](#)” User Manual).

To create a point cloud during dense DEM creation using the SGM method, set the **Create** checkbox in the **Point cloud (LAS)** section of the **SGM parameters** window. To record IR-band data into the LAS file under creation, click **Parameters** button in the **Point cloud (LAS)** section and set the **Classify vegetation by IR channel (if available)** checkbox in the **LAS creation parameters** window.

The point cloud created in this way by tools of *PHOTOMOD* software (if the source images have an IR channel) contains the necessary data to perform the classification described below.



The value of the **point class** parameter initially depends on the data provider (the point may be not classified), and later on - on the subsequent processing that the point cloud is subjected to.



The system also provides for the classification of a DEM according to *NDVI*, that is carried out in a similar way (see “DEM classification” in the “[DTM Generation](#)” User Manual).

To classify vegetation in the territory described by the point cloud, perform the following:

1. Select **Terrain > LAS > Classification by NDVI**. The **Classification by NDVI** window opens.

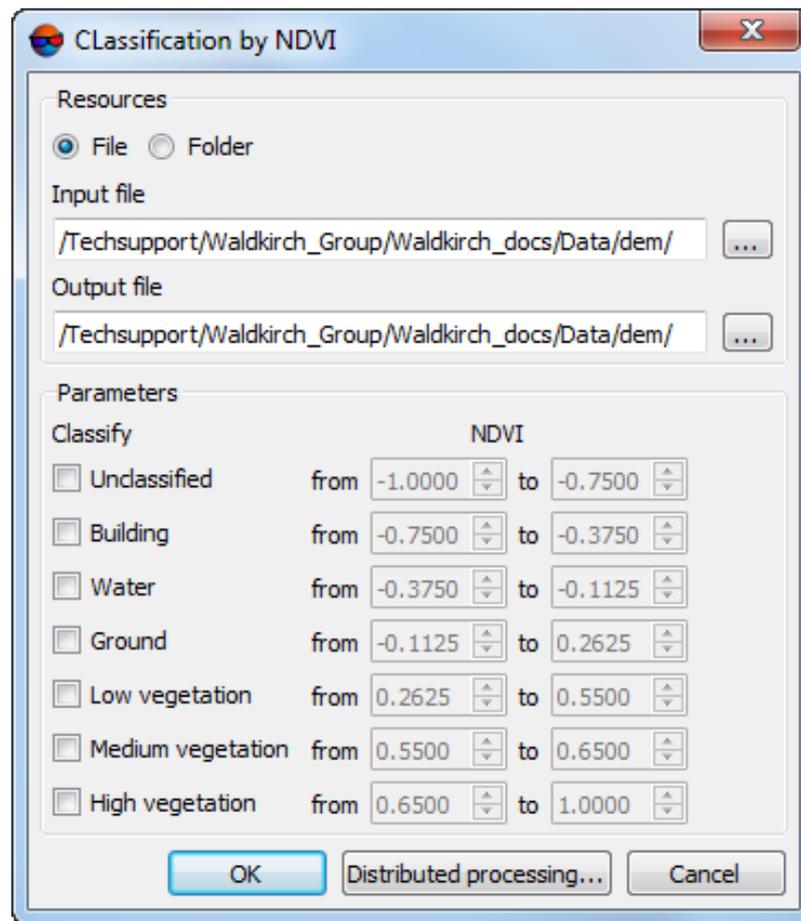


Fig. 30. The Classification by NDVI window

2. Select the input **Resources**:
 - [optional] **File** – to process a point cloud saved as a single file;
 - [optional] **Folder** – to process a fragmented point cloud.
3. Click the button to specify a path to the source data;
4. Click the button to specify target folder for output LAS-file(s) in active profile resources;
5. Set the **parameters** for classification. To assign one of expected classes to points, set the appropriate checkbox, and edit the default range of NDVI values, if needed.



Common NDVI value limits are from -1 to 1. Values from -1 to 0 are reserved for infrastructure objects, as well as for non-wildlife objects (e.g. snow, water, sand, stones, houses, roads, etc.). Values for vegetation are between 0 and 1.



Ranges of NDVI-index values whereby points will be classified, should not overlap each other (since more than one value of the Class parameter cannot be assigned to a point).

Before starting the operation, an appropriate check is performed. In case of overlapping between NDVI ranges, an appropriate message is issued.

6. Click OK. To perform classification through the distributed processing, perform the following:
 1. Configure and start the server/client of distributed processing (see “Distributed processing” in the “[General information](#)” User Manual).
 2. Click the **Distributed processing** button.
7. After the successful completion of the operation, an appropriate message is displayed. The processed LAS files are created in the output folder. The points of the processed files have the values of the **Point class** parameter filled in (see the [LIDAR data loading and displaying](#) chapter).

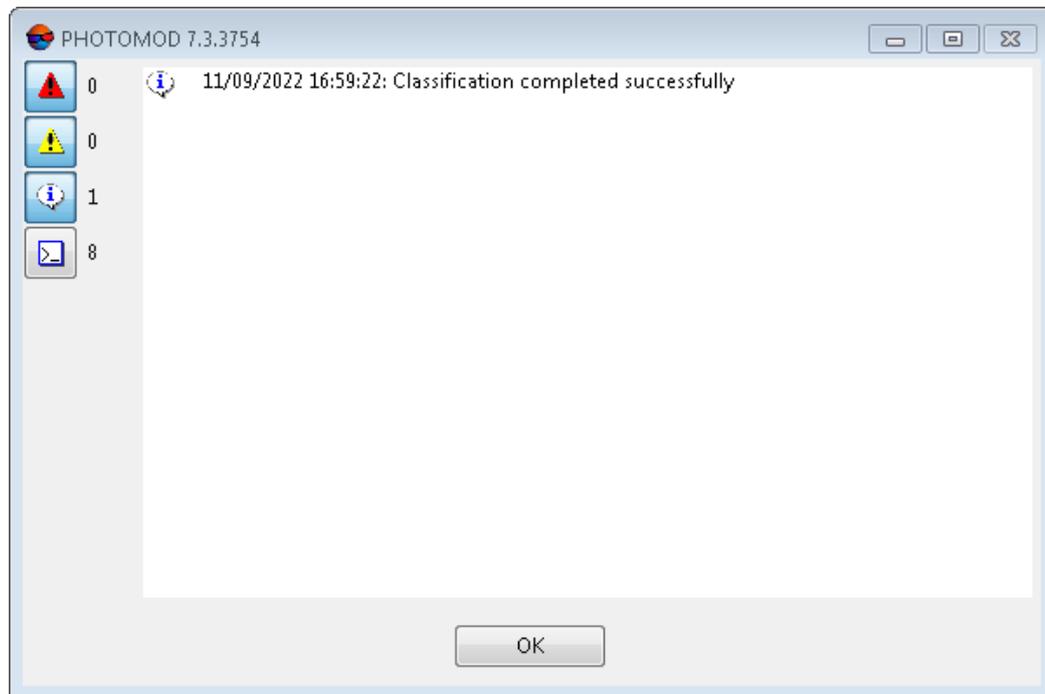


Fig. 31. The info message

4.6.2. Manual point groups classification

The system provides for group attributing the following **point classes** to lidar points:

- **Ground;**
- **Low vegetation;**

- **Medium vegetation;**
- **High vegetation;**
- **Road surface;**
- **Building;**
- **Wall;**
- **Furniture;**
- **Water;**
- **Car;**
- **Wire - conductor (phase).**
- **Transmission tower.**



Data on the **point classes** are recorded in a LAS file after the user clicks the appropriate **Load LAS** toolbar button (without requiring additional confirmation from the user).

It is impossible to undo this operation (the user only has the opportunity to edit the selected group of points later again in the same way). It is recommended to back up the relevant files (resources) before manual classification.

To assign manually **point class** attributes to selected groups of lidar points, perform the following:

1. Open the **Load LAS** window;
2. Open the LAS file located in the *Windows* file system or in the active profile resources;



The LAS file under processing which is located in the *Windows* file system is to be recordable (for example, not open in other running *PHOTOMOD* modules or in other programs).



Click the  button to enable the coloring mode to accordance with objects classification.

3. **Select** the desired lidar points groups;
4. To assign one of available **point classes** to the selected point groups, click the appropriate button in the **Load LAS** window toolbar intended for manual lidar point classification:

Table 7. Toolbar allowing to classify LIDAR data

Buttons	Functions
	assign the low vegetation standard class to manually selected  lidar points (3)
	assign the medium vegetation standard class to manually selected lidar points (4)
	assign the high vegetation standard class to manually selected lidar points (5)
	assign the road surface standard class to manually selected lidar points (11)
	assign the ground standard class to manually selected lidar points (2)
	assign the building standard class to manually selected lidar points (6)
	assign the wall class to manually selected lidar points (66). This class is used in <i>PHOTOMOD</i> and is not a part of the <i>ASPRS</i> -developed standard classification . <i>PHOTOMOD</i> software uses one of the user definable classes, considering it as wall , inside the <i>PHOTOMOD</i> system
	assign the furniture class to manually selected lidar points (65). This class is used in <i>PHOTOMOD</i> and is not a part of the <i>ASPRS</i> -developed standard classification. <i>PHOTOMOD</i> software uses one of the user definable classes, considering it as furniture , inside the <i>PHOTOMOD</i> system
	assign the water standard class to manually selected lidar points (9)
	assign the car class to manually selected lidar points (64). This class is used in <i>PHOTOMOD</i> and is not a part of the <i>ASPRS</i> -developed standard classification. <i>PHOTOMOD</i> software uses one of the user definable classes, considering it as car , inside the <i>PHOTOMOD</i> system
	assign the wire - conductor (phase) standard class to manually selected lidar points (14)
	assign the transmission tower standard class to manually selected lidar points (15)
	assign the Created, never classified standard class to manually selected lidar points (0)

5. After the classification is complete, click  in the **Load LAS** window toolbar to disable the lidar point group selection mode.

4.6.3. Switching classes

The system allows for switching some classes of a classified point cloud to others.

For this, perform the following:

1. Choose **Terrain > LAS > Remap classes**. The **Remapping classes** window opens:

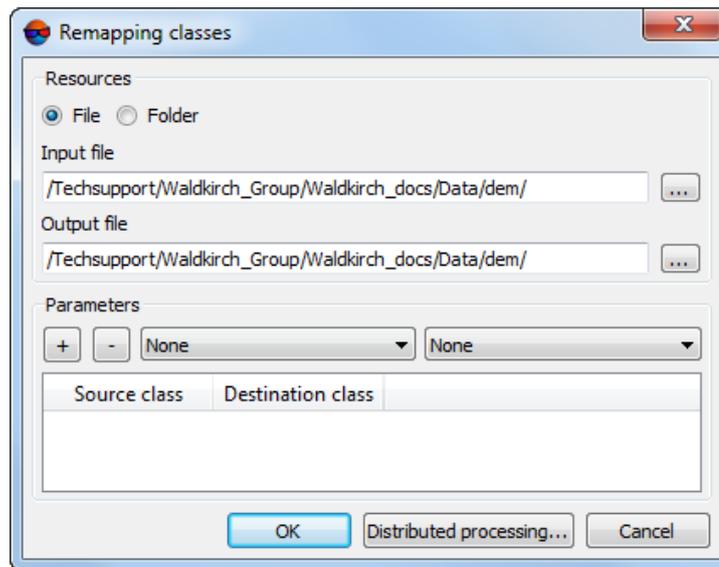


Fig. 32. The Remapping classes window

2. Select the input **Resources**:
 - [optional] **File** – to process a point cloud saved as a single file;
 - [optional] **Folder** – to process a fragmented point cloud.
3. Click the **...** button to specify a path to the source data;
4. Click the **...** button to specify target folder for output LAS-file(s) in active profile resources;
5. Set **parameters** for reassigning classes:
 1. In the appropriate drop-down lists, select the **original class** and its **update**;
 2. Click **+** to create a new rule for class reassigning. The new rule is tabled in the lower part of the window;



The system allows you to reclassify a previously unclassified point cloud in its entirety.



The reclassification operations are performed simultaneously, so the order of the reclassification rules does not affect the result output in any way.



Reclassification rules cannot be duplicated.

3. [optional] To delete one or more class reassigning rules, select the required lines in the table in the lower part of the window holding the left mouse button and click .
6. Click OK. To reassign classes using the distributed processing, perform the following:
 1. Configure and start the distributed processing server/client (see the “Distributed processing” in the “[General information about system](#)” User Manual).
 2. Click the **Distributed processing** button.

4.7. Building a histogram by a point cloud

The system provides for building a histogram by a point cloud:

- according to LIDAR points NDVI index, if the intensity of the reflected color in the infrared band values (which are involved in NDVI index calculation) are available in the LAS file;
- according to LIDAR points classification (if such data are available in the LAS file).



Note, that point class is the property of a lidar point that can be recorded in a LAS file (optionally, if such data is available), while the NDVI index is calculated by the system when accessing a particular point.

NDVI is the ratio between the difference in the intensities of reflected light in the red (Red) and near infrared (NIR) bands and their sum:

$$\text{NDVI} = (\text{NIR} - \text{RED}) / (\text{NIR} + \text{RED})$$



The value of the **point class** parameter initially depends on data provider (the point may be not classified), and later on – on the subsequent processing that the point cloud was subjected to (for example, lidar point [classification](#) according to the NDVI index, using the *PHOTOMOD* software tools, performed with user settings).

Thereof, in the latter case (depending on the settings specified by the user during the latest classification) the mutual ratio of the current **point class** and the calculated NDVI index may not comply with common standards.

To build a histogram, perform the following:

1. Select **Terrain > LAS > Load LAS...** to open the **Load LAS** window;
2. Click  or  in the **Load LAS** toolbar to open a lidar data file. Select one or more LAS files.



An integrated histogram will be built for all point clouds displayed in the workspace in the right part of the **Load LAS** window.



To display any given point cloud in the workspace in the right part of the **Load LAS** window, set the appropriate checkbox in the list of loaded LAS files.

3. Perform one of the following actions:

- [optional] Click the  toolbar button to build the histogram according to LIDAR points NDVI index;
- [optional] Click the  toolbar button to build the histogram according to LIDAR points classification.

Wait until the histogram is built. The **Histogram** window opens:

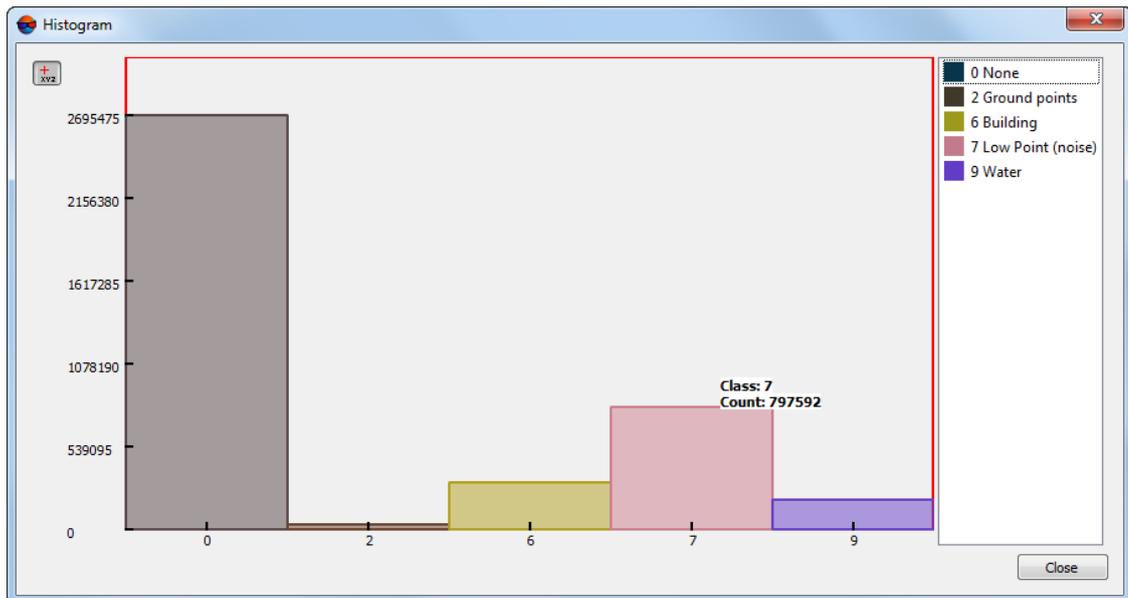


Fig. 33. The Histogram window (according to LIDAR points classification)

The histogram displays:

- [optional] the distribution of the number of lidar points (**Y-axis**) within the range of possible NDVI-index values: from -1 to 1;
- [optional] the distribution of points by class.

To display a tooltip with the exact values of the number of points and the range of NDVI values (or class affiliation) when you hover over an individual diagram column, click  button.



To disable the tooltip mode, click the  button.

5. LAS filtering

5.1. LAS filtering by elevations and numbers of reflected pulses

The system provides possibility to filter lidar data and point clouds (obtained as a result of DEM creation using the SGM method), by elevations and numbers of reflected pulses in each point, to remove accident surges.

When filtering accident surges, the system provides possibility to use the reference surface of DEM (created together with the LAS cloud of points, or covering the same territory – see the “Dense DEM generation using SGM method” chapter of the “[DTM Generation](#)” User Manual).

In order to filter LIDAR data perform the following actions:

1. [optional] Load the project and reference DEMs;
2. Choose **Terrain** > **LAS** > **Filter LAS...**. The **LAS filtering** window opens;

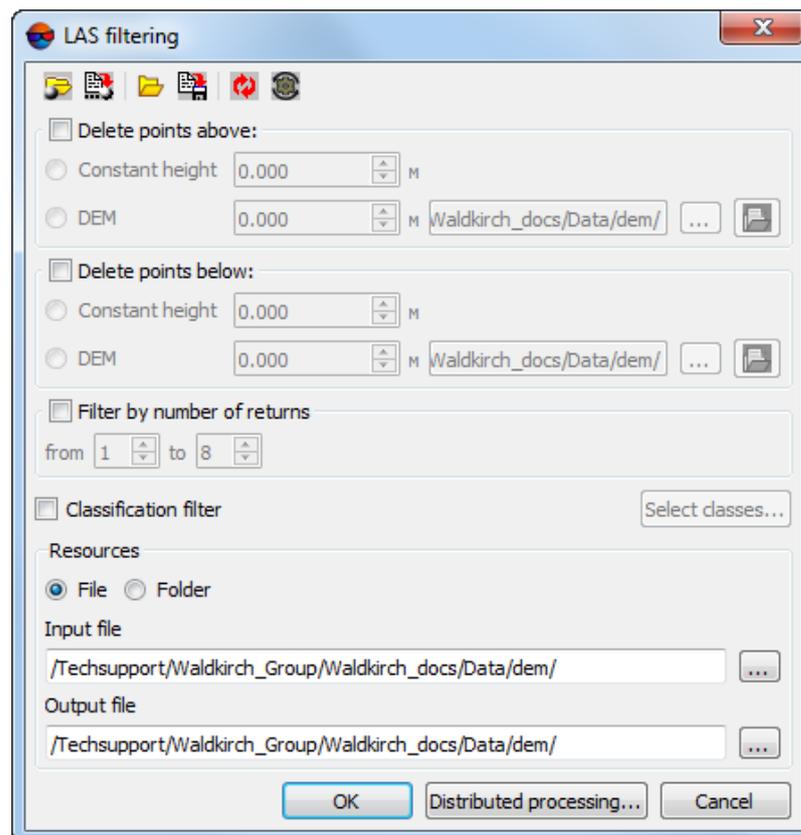


Fig. 34. The LAS filtering window

A toolbar in the upper part of the window is intended to save/load parameter's settings and contains the following buttons:

-  – allows to load parameter’s settings saved previously to active profile resources;
 -  – allows to save all parameter’s settings to *.x-.ini file located in active profile resources;
 -  – allows to load parameter’s settings from *.x-.ini file located in a folder of Windows file system;
 -  – allows to save parameter’s settings to *.x-.ini file located in a folder of Windows file system;
 -  – allows to restore the last-session’s settings;
 -  – allows to restore default parameter’s settings.
3. Select the input **Resources**:
 - [optional] **File** – to process a point cloud saved as a single file;
 - [optional] **Folder** – to process a fragmented point cloud.
 4. Click the  button to specify a path to the source data;
 5. Click the  button to specify target folder for output LAS-file(s) in active profile resources;
 6. [optional] set the **Delete points above** checkbox and adjust LAS filtering settings by the elevation:
 - **Constant height** – set the height in meters (all points above the preselected height will be removed);
 - **DEM** – click the  button to select DEM as a reference surface in the active profile resources. Enter the value of permissible elevation above the DEM surface, in meters (all points above the DEM surface will be removed, except for those not exceeding the given permissible elevation).
-  Click the  button to open the **Layer selection** window and select the source DEM from the list of DEMs uploaded to the project.
-  Too low or zero values of the permissible elevation may cause removal of “good” points, and hence, “sparse” point cloud.
- Recommended value is no less than RMS by Z in stereopairs (see the “Brief residuals report” chapter of the “[Block adjustment](#)” User Manual).

7. [optional] set the **Delete points below** checkbox and adjust LAS filtering settings by the elevation:

- **Constant height** – set the height in meters (all points below the preselected height will be removed);
- **DEM** – click the  button to select DEM as a reference surface in the active profile resources. Enter the value of permissible deviation from the DEM surface, in meters (all points below the DEM surface will be removed, except for those not exceeding the given permissible deviation).



Click the  button to open the **Layer selection** window and select the source DEM from the list of DEMs uploaded to the project.



For correct filter operation, *in case of filtering points below the DEM surface*, the reference DEM should be the digital terrain model, i.e. *do not include data on buildings and vegetation*.

To create such a reference DEM, it is recommended to use *Buildings and vegetation filter* or *Slope based filter* (see the “DEM filtering” chapter of the “[DTM Generation](#)” User Manual).

Recommended permissible deviation value is no less than RMS by Z in stereopairs (see the “Brief residuals report” chapter of the “[Block adjustment](#)” User Manual).

8. [optional] set the **Filter by number of returns** checkbox to adjust LAS filtering settings according to the number of reflected pulses in every point (in case of available data of such type in the LAS format file);



When filtering the cloud of points, created during the DEM creation using the SGM method, this parameter has somewhat different meaning.

In this case, in the LAS file, the number of reflected pulses in the given point is the number of stereopairs on the basis of which a particular point was calculated: 1, 2, 3, 4, 5, 6, 7, or 8.

Limitation of the “number of reflected pulses” by 1 to 8 results from the limitations of the LAS format itself, accordingly, in the latter case, the number of stereopairs can be both “8” and “8 and more”.

It is recommended to filter points calculated on the base of two and less stereopairs. Too strict filtering settings in relation to used stereopair numbers can result in removing “good” points, and hence “sparse” cloud of points (and therefore it may not to display some objects).

9. [optional] set the **Classification filter** checkbox to set LAS filtering parameters according to the classification of points (see the LAS [specification](#) published by *ASPRS* and [Appendix A](#));

Click **Select classes**. The **LAS classification filter parameters** window opens:

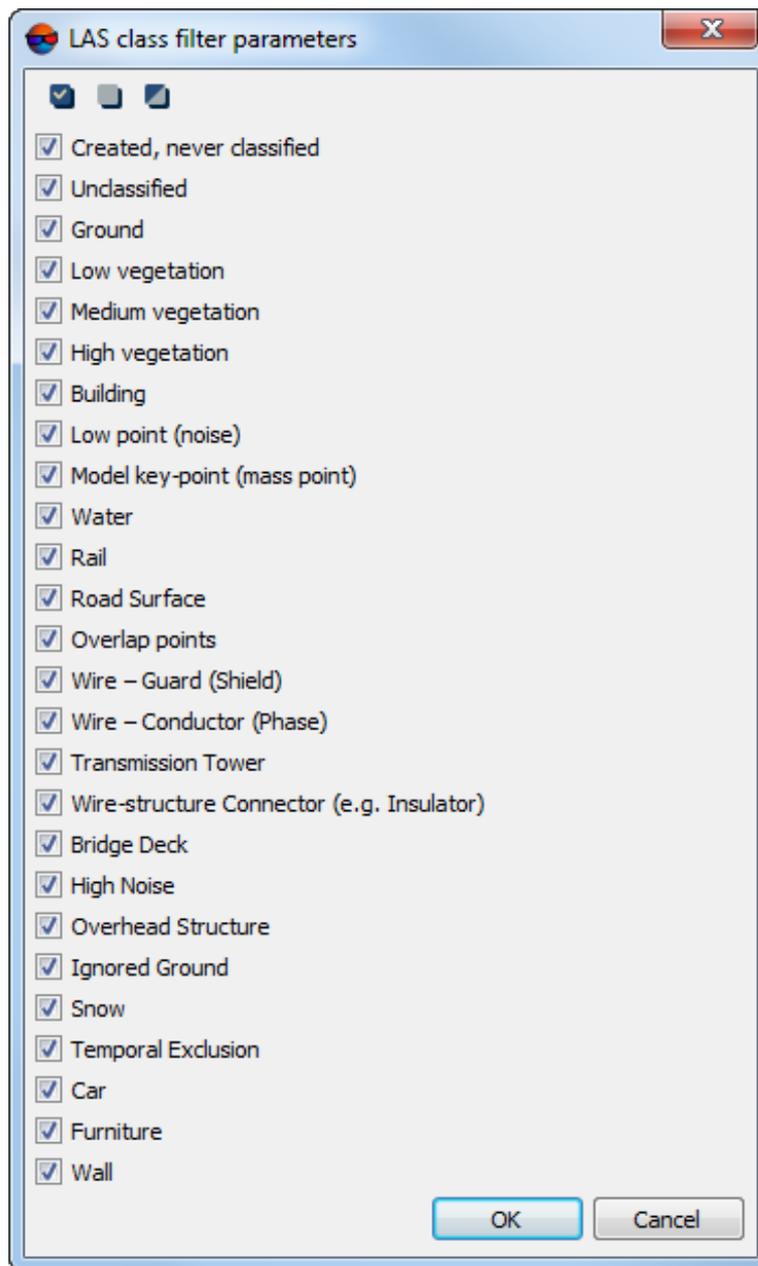


Fig. 35. The LAS classification filter parameters window

To remove LAS points ranked in a certain way from the resulting file, clear the appropriate checkboxes. For group selection of point classes, the following buttons are provided in the **LAS classification filter parameters** window:

-  – allows user to select all the classes of lidar points;
-  – allows user to deselect all classes of lidar points;
-  – allows user to invert selection of point classes.

10. Click OK. As a result, processed LAS files will be created in the **Destination folder** having the names identical to the file names in the Initial folder.

In order to filter LAS using distributed processing, do the following:

1. Change settings and run the distributed processing server/client (see the “Distributed processing” chapter in the “General information about system” User Manual).
2. Click the **Distributed processing** button.

5.2. LAS smooth filter

The system allows for point cloud filtering to eliminate noise.

In order to filter LIDAR data perform the following actions:

1. Choose **Terrain > LAS > LAS smooth filter**. The **LAS filtering** window opens;

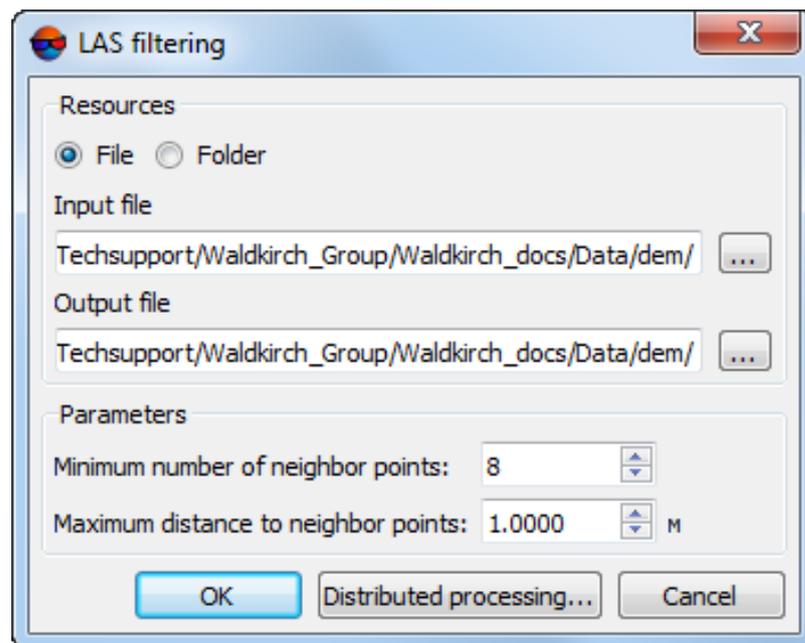


Fig. 36. The LAS filtering window

2. Select the input **Resources**:
 - [optional] **File** – to process a point cloud saved as a single file;
 - [optional] **Folder** – to process a fragmented point cloud.
3. Click the **...** button to specify a path to the source data;

4. Click the  button to specify target folder for output LAS-file(s) in active profile resources;
5. Set the following filtering **parameters**:
 - **Maximum distance to neighbor points** (in the projects units) – a search radius for neighbor points;
 - **Minimum number of neighbor points** – the least number of neighbor points. When not enough, a point is removed.



Recommended **Minimum neighborhood points count** is about 6 or 8 (set by default).

6. Click OK. As a result, processed LAS files will be created in the **Destination folder** having the names identical to the file names in the Initial folder.

In order to filter LAS using distributed processing, do the following:

1. Change settings and run the distributed processing server/client (see the “Distributed processing” chapter in the “[General information about system](#)” User Manual).
2. Click the **Distributed processing** button.

5.3. LAS bilateral filter

The system allows for smoothing point cloud filtering to remove “noise” errors taking into account points color (if such data are available in the LAS file).

In order to filter LIDAR data perform the following actions:

1. Choose **Terrain > LAS > LAS bilateral filter**. The **Bilateral filter LAS** window opens;

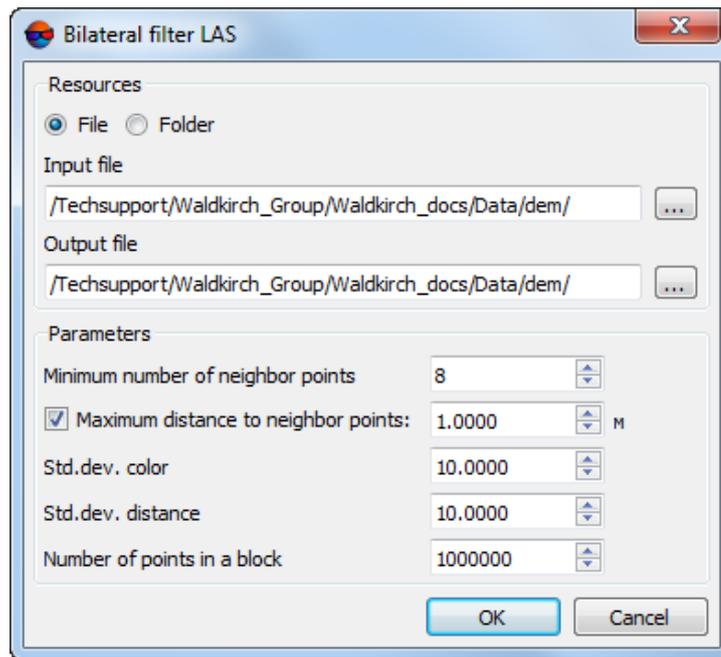


Fig. 37. The Bilateral filter LAS window

2. Select the input **Resources**:
 - [optional] **File** – to process a point cloud saved as a single file;
 - [optional] **Folder** – to process a fragmented point cloud.
3. Click the **...** button to specify a path to the source data;
4. Click the **...** button to specify target folder for output LAS-file(s) in active profile resources;
5. Set the following filtering **parameters**:
 - **Minimum number of neighbor points** involved into computations for the given point;
 - [optional] To limit **Maximum distance to neighbor points**, set the appropriate checkbox and set the neighbor point search radius, in the project's units;
 - **Std. dev. color**, allows to limit weight influence of neighbor points, depending on their color characteristics;



With the minimum standard deviation, the filtering process will take into account the influence of only the closest in color neighboring points. At the limit values of the standard deviation, all points with the maximum weight will be taken into account, regardless of their color.

- **Std. dev. distance**, allows to limit the weigh influence of neighbor points, depending on their distance to the point for which the calculations are made;
- **A Number of points in a block** allows to divide a large point cloud into sequentially processed fragments (blocks).



The recommended approximate size of a processed block for workstations with RAM no less than 16 Gb is about 2 million points.

6. Click OK. As a result, processed LAS files will be created in the **Destination folder** having the names identical to the file names in the Initial folder.

5.4. LAS statistical outlier removal

The system allows to filter rough errors, i.e. single points beyond the main cloud at some distance from it, that are very likely erroneous data.

In order to filter LIDAR data perform the following actions:

1. Choose **Terrain > LAS > LAS statistical outlier removal**. The **LAS statistical outlier removal filter** window opens;

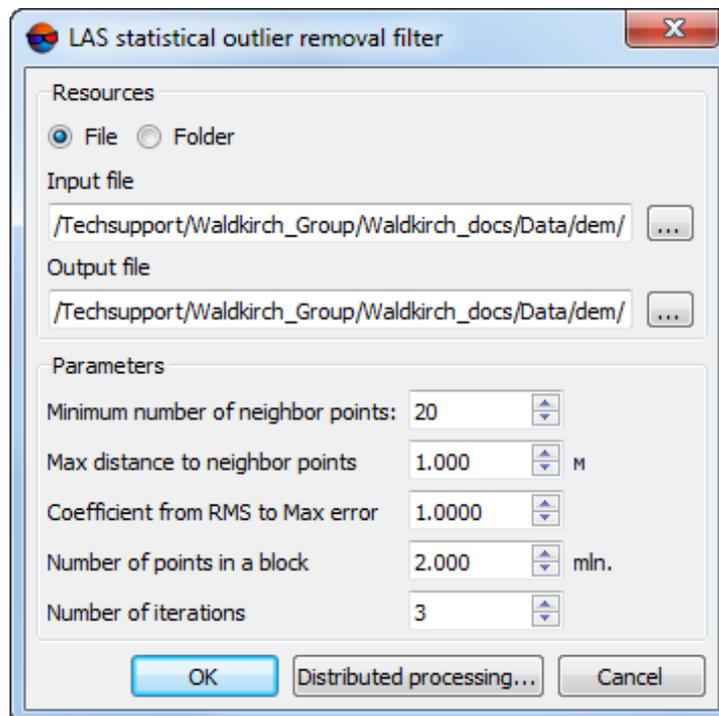


Fig. 38. The LAS statistical outlier removal filter window

2. Select the input **Resources**:

- [optional] **File** – to process a point cloud saved as a single file;
 - [optional] **Folder** – to process a fragmented point cloud.
3. Click the  button to specify a path to the source data;
 4. Click the  button to specify target folder for output LAS-file(s) in active profile resources;
 5. Set the following filtering **parameters**:
 - **Minimum number of neighbor points** is the number of neighbor points for the given point not to be deleted;
 -  Recommended **minimum number of neighbor points** is about 6-8 (default).
 - **Max distance to neighbor points** allows to set the range where the search for neighbor points will be made (in the project's units);
 - **Coefficient from RMS to Max error** – affects further filtering of points having sufficient **minimum number of neighbor points**;
 -  The **Coefficient from RMS to Max error** is used when calculating the tolerance for the average distance between points in a cloud. The increase of this parameter causes the increased tolerance. The decrease of this parameter's value leads to stricter point filtering.
 -  This tolerance is calculated as follows:
 - The product of the standard deviation of the distance between points (over the entire cloud) and the Coefficient from RMS to Max error is calculated;
 - This product is added to the average distance between points in the cloud.
 - **Number of points in a block** allows to divide a large point cloud into fragments (block) processed sequentially.
 -  The recommended approximate size of a processed block for workstations with RAM no less than 16 Gb is about 2 million points.
 - **Number of iterations.**
 6. Click OK. As a result, processed LAS files will be created in the **Destination folder** having the names identical to the file names in the Initial folder.

In order to filter LAS using distributed processing, do the following:

1. Change settings and run the distributed processing server/client (see the “Distributed processing” chapter in the “General information about system” User Manual).
2. Click the **Distributed processing** button.

5.5. LAS fusion

The system allows for point cloud filtering to remove noise taking into account averaged normals from processed points to projection centers of images used in their calculation (if such data are available in a LAS file, see “Dense DEM generation using SGM method” in the “DTM Generation” User Manual).

Filtering is carried out by averaging adjacent points in order to find the optimal surface. Points are filtered within the constructed cylinder, with user-specified parameters. The axis of this cylinder is the averaged normal from the point being processed.

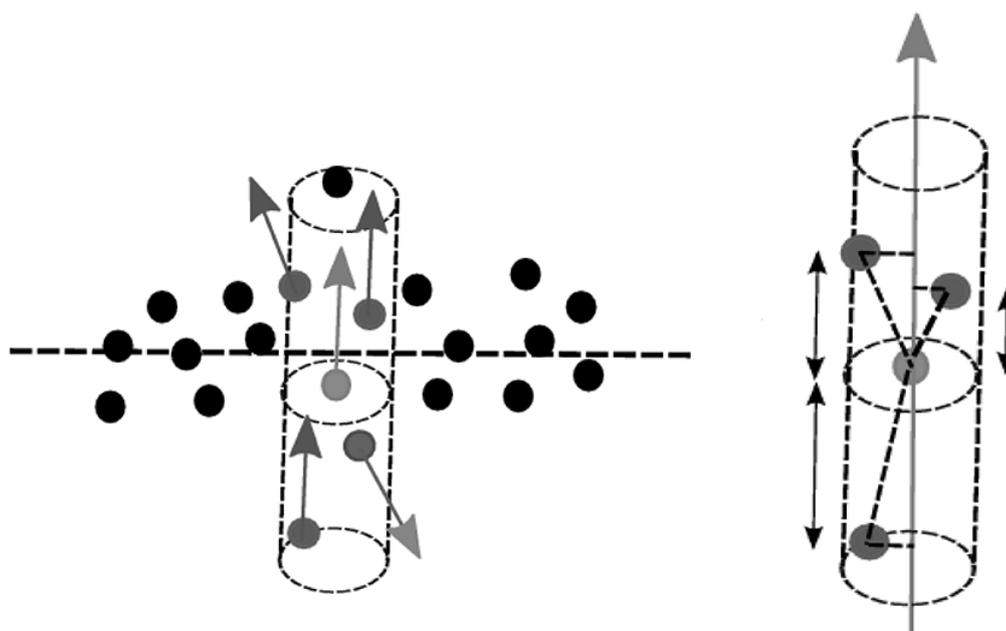


Fig. 39. Filter working principle

In order to filter LIDAR data perform the following actions:

1. Choose **Terrain > LAS > LAS fusion**. The **LAS fusion filter** window opens;

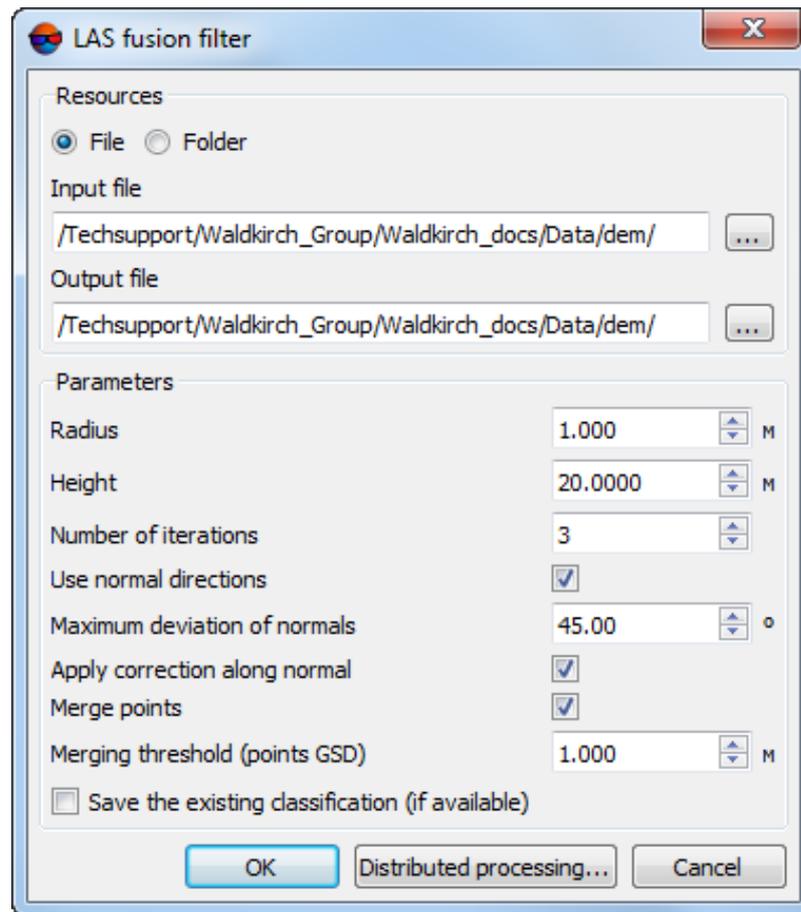


Fig. 40. The LAS filtering window

2. Select the input **Resources**:
 - [optional] **File** – to process a point cloud saved as a single file;
 - [optional] **Folder** – to process a fragmented point cloud.
3. Click the button to specify a path to the source data;
4. Click the button to specify target folder for output LAS-file(s) in active profile resources;
5. Set the filtering **parameters**:
 - Cylinder's **radius**;
 - Cylinder's **height**;
 - **Number of iterations**;

- To account for directions of point normals, set the **use normal directions** checkbox. In this case, with each subsequent iteration, the direction of the processed point normal is corrected according to the changes made by the filter, otherwise it remains unchanged relative to its original position;
 - Set the **maximum deviation of normals**. Points that fall into the processing area are excluded from the calculations if the deviation of their normals from the cylinder axis exceeds the specified value;
 - To calculate the correction along the normal, set the **Apply correction along normal** checkbox. In this case, at each subsequent iteration, the position of the processed point relative to the cylinder's axis is corrected according to the changes made by the filter, otherwise the point is not shifted relative to the cylinder's axis;
 - To **merge points** set the appropriate checkbox;
 - Specify the **merging threshold** (set the output points cloud GSD).
 - To **save the existing classification (if available)** set the appropriate checkbox.
6. Click OK. As a result, processed LAS files will be created in the **Destination folder** having the names identical to the file names in the Initial folder.

In order to filter LAS using distributed processing, do the following:

1. Change settings and run the distributed processing server/client (see the “Distributed processing” chapter in the “[General information about system](#)” User Manual).
2. Click the **Distributed processing** button.

5.6. Buildings and vegetation filter

The system provides for recognizing and deletion of LIDAR points which describe such objects as buildings, trees or cars. For that filter of buildings and vegetation id used. After its work only points that describe terrain relief are remain in the point cloud.



The building and vegetation filter does not take into account the current classification of lidar points, their colors, or other characteristics. The system analyzes nothing but the mutual arrangement of points, which determines the shape of the surface described by the point cloud and its individual fragments.

To filter such an objects perform the following actions:

1. Choose **Terrain › LAS › LAS Buildings and vegetation filter**. The **Points cloud filtering** window opens:

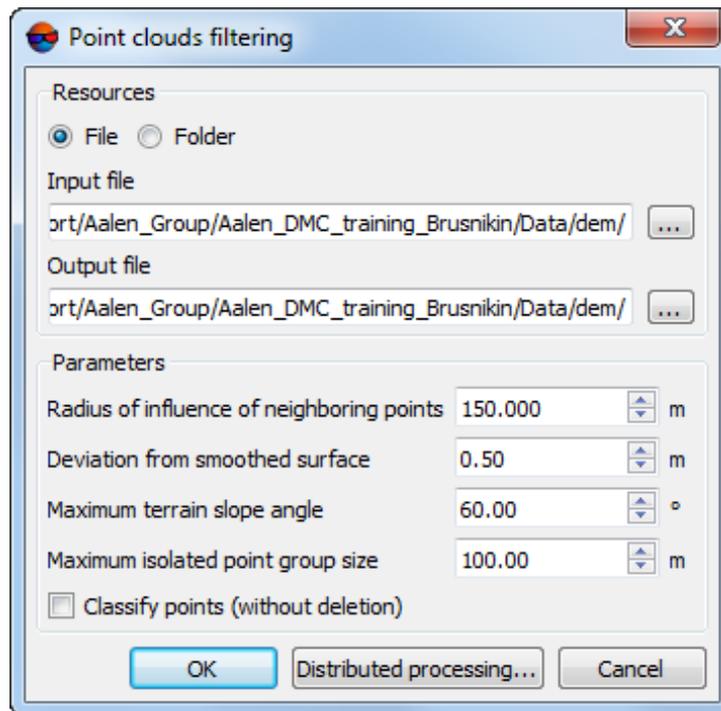


Fig. 41. Parameters of buildings and vegetation filter

2. Select the input **Resources**:
 - [optional] **File** – to process a point cloud saved as a single file;
 - [optional] **Folder** – to process a fragmented point cloud.
3. Click the  button to specify a path to the source data;
4. Click the  button to specify target folder for output LAS-file(s) in active profile resources;
5. Set the following filtering **parameters**:
 - The **Radius of influence of neighboring points** influence on a point under processing, in project units. It is recommended to specify the **Radius of neighbor points** close to the characteristic linear dimensions of anthropogenic objects located in a given territory;
 -  A notable increase in this parameter (and, accordingly, the number of “neighbors” participating in the calculations) can negatively affect the workstation’s performance.
 - Maximal **deviation from smoothed surface** calculated during the filtering to delete points located at a distance greater than the specified one;

- **Maximum terrain slope angle**, typical for a given territory;



The slope angle is one of the parameters that determines the building filtering threshold. Reducing the slope angle may result in removing some terrain features (e.g., hills of similar shape and size) along with the buildings.

- **Maximum isolated point group size** (in XY-plane) which allows us to determine the maximum area of objects described by such groups and located at a distance from a certain plane formed by neighboring points.

As a rule, these are separate objects located on the roofs of buildings. Their surfaces are noticeably separated from the plane of the roof itself



The filter is not applied to objects whose area is greater than the value determined by the specified characteristic linear dimensions.

6. [optional] To **classify points (without deletion)**, set the appropriate checkbox. All cloud points (regardless of the existing classification) will be divided into two classes: **ground** and **buildings**.
7. Click OK. As a result, processed LAS files will be created in the **Destination folder** having the names identical to the file names in the Initial folder.

In order to filter LAS using distributed processing, do the following:

1. Change settings and run the distributed processing server/client (see the “Distributed processing” chapter in the “[General information about system](#)” User Manual).
2. Click the **Distributed processing** button.

5.7. Manual deleting point groups

To delete some lidar points, [select](#) the required point groups, press **Delete** and confirm this operation in the appropriate dialog box by clicking **Yes**:

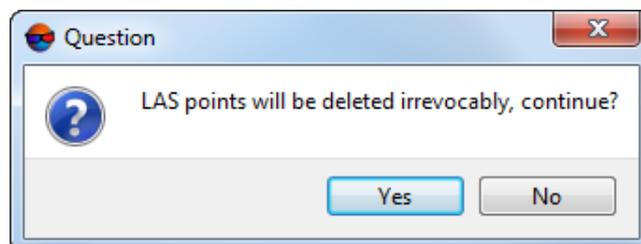


Fig. 42. A dialog box to confirm deletion of lidar points

The relevant LAS-file (or LAS-files, if the point cloud was divided into tiles and the deletion operation affected points in several tiles at once) is overwritten when the user clicks **Yes**. It is impossible to undo this operation. Before making changes to the original files or resources, the system automatically creates their backup copies located in the backup folder, which is automatically created in the same folder as the edited point cloud (in the *Windows* file system or in the active profile resources).

A name of the backup copy is created according the following pattern: <original file name>.<data yyyy-mm-dd>.<time hh-mm-ss>.las, for example, Block_1_1_0.2023-08-29.17-09-02.las. If necessary, data restoration from backups is carried out manually by the user.

To set the number of backup copies to be created, choose **Service > Settings** or click  in the main toolbar. In the **Settings** window that opens, in the **Backups** tab, set the **Number of stored backup copies (per resource) for vector data / point clouds**. If the specified number of backups is exceeded, earlier copies are deleted.

Appendix A. ASPRS Standard Point Classes

Table A.1. Objects classification contained in reflection points attributes according to specification published by ASPRS (LAS v.1.4, point data record formats 6-10)

Classification Value	Meaning
0	Created, never classified ()
1	Unclassified
2	Ground ()
3	Low Vegetation ()
4	Medium Vegetation ()
5	High Vegetation ()
6	Building ()
7	Low Point (noise)
8	<i>Reserved</i>
9	Water ()
10	Rail
11	Road Surface ()
12	<i>Reserved</i>
13	Wire – Guard (Shield)
14	Wire – Conductor (Phase) ()
15	Transmission Tower ()
16	Wire-structure Connector (e.g. Insulator)
17	Bridge Deck
18	High Noise

Classification Value	Meaning
19	Overhead Structure (e.g., conveyors, mining equipment, traffic lights)
20	Ignored Ground (e.g., breakline proximity)
21	Snow
22	Temporal Exclusion (Features excluded due to changes over time between data sources – e.g., water levels, landslides, permafrost)
23-63	<i>Reserved</i>
64-255	User Definable



Created, never classified (0), Ground (2), Low vegetation (3), Medium Vegetation (4), High vegetation (5), Building (6), Water (9), Road surface (11), Wire – Conductor (Phase) (14) and Transmission Tower (15) classes can be assigned to point groups during [manual classification](#).



The **car** class () , the **wall** class () and the **furniture** class () are used in *PHOTOMOD* and is not a part of the *ASPRS*-developed [standard classification](#). *PHOTOMOD* software uses one of the user definable classes, considering it as **car** (64), **wall** (66) and **furniture** (65) inside the *PHOTOMOD* system.



Classes assigned to DEM cells are automatically considered during DEM conversion in a LAS point cloud (see “DEM classification” and “Convert DEM to point cloud (LAS)” in the “[DTM Generation](#)” User Manual).