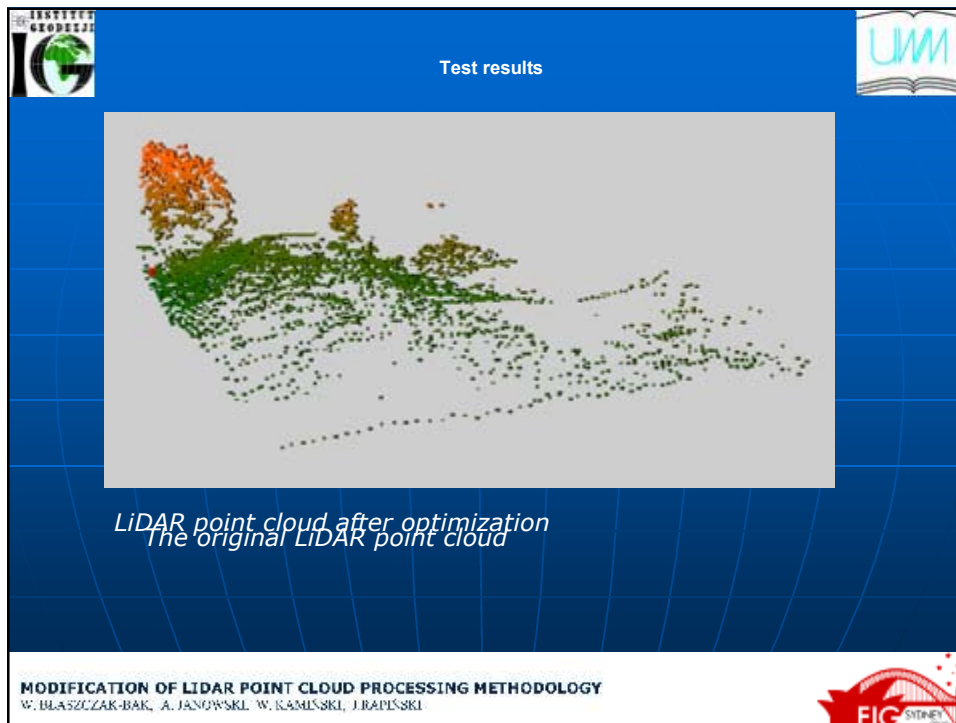


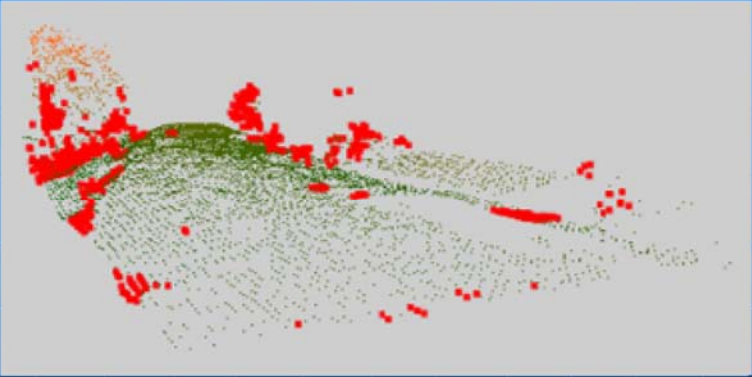
Test results												
Scenario no.	Number of points in original data set.	Number of points removed during optimisation.	Number of points after optimisation.	Optimisation time [sec]	Size of moving window	Number of points removed during filtration.	Number of points after filtration (points for DTM)	Time of Huber processing [sec.]	Total operation time	Number of points removed during filtration.	Number of points after filtration (points for DTM)	Time of Huber processing [sec.]
I	15 000	10 089	4911	5	1mx1m	4	4 907	1	6	8	14 992	1
II	15 000	10 089	4911	5	3mx3m	120	4 791	1	6	620	14 380	5
III	15 000	10 089	4911	5	5mx5m	267	4 644	5	10	758	14 242	39
IV	15 000	10 089	4911	5	7mx7m	293	4 618	17	22	801	14 199	136
V	15 000	10 089	4911	5	10mx10m	392	4 519	30	35	925	14 075	491
VI	15 000	10 089	4911	5	15mx15m	466	4 445	151	156	819	14 181	2415

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Test results



The original LiDAR point cloud after false filtering using scenario VI

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FIG SYDNEY

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Thank You

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FIG SYDNEY