## For the outlier remover filter,

1. set the number of neighboring points to analyze for any given point

2. Set threshold scale factor

x = 1.0

# Any point with a mean distance larger than global (mean distance+x\*std\_dev) will be considered outlier

## For the voxel grid downsampling

The leaf\_size should be adjusted

## For the passthrough filter

The axis minimum and maximum value should be adjusted

## For the plane segmentation

The maximum distance should be defined

## For the Euclidean clustering

The cluster tolerance, the minimum cluster size and maximum cluster size should all be defined

1. filtering and RANSAN plane fitting for each step

2. cluster segmentation

3. provide the normalized confusion matrix for three different test environments and object recognition

4.





