The first step directly runs A_feature_detection.exe to get the feature point set.

1.The first row is the path of the point cloud with normals.

2.The second row is the K-nearest neighbor.

3.The third row saves the number of feature points.

The generated feature point set file (my_point.txt) is saved in the D drive.

The second step directly runs A_line_segment_extraction to get the line segment set.

The generated line segment set file (lines.txt) is saved in the D drive.

If you use the executable program we provide, please cite the following article.

@article{liu2023robust,

title={Robust and Accurate Feature Detection on Point Clouds},

author={Liu, Zheng and Xin, Xiaopeng and Xu, Zheng and Zhou, Weijie and Wang, Chunxue and Chen, Renjie and He, Ying},

year={2023}

}

@article{xin2024accurate,

title={Accurate and complete line segment extraction for large-scale point clouds},

author={Xin, Xiaopeng and Huang, Wei and Zhong, Saishang and Zhang, Ming and Liu, Zheng and Xie, Zhong},

journal={International Journal of Applied Earth Observation and Geoinformation},

volume={128},

pages={103728},

year={2024},

publisher={Elsevier}

}