**成品按照交付模板的格式给出**

[Point Cloud Library (PCL): pcl::SpinImageEstimation< PointInT, PointNT, PointOutT > Class Template Reference (pointclouds.org)](https://pointclouds.org/documentation/classpcl_1_1_spin_image_estimation.html)



只分析类中的computeSiForPoint接口。

[Point Cloud Library (PCL): pcl::UniqueShapeContext< PointInT, PointOutT, PointRFT > Class Template Reference (pointclouds.org)](https://pointclouds.org/documentation/classpcl_1_1_unique_shape_context.html)



只分析类中的computePointDescriptor接口。