R topics documented:

Collate 'Class-LASHeader.r' 'Class-LAS.r' 'Class-LAScatalog.r'
 'Class-LAScluster.r' 'RcppExports.R' 'algorithm-dec.r'
 'algorithm-dsm.r' 'algorithm-gnd.r' 'algorithm-itd.R'
 'algorithm-its.r' 'algorithm-shp.r' 'algorithm-snag.r'
 'algorithm-spi.r' 'catalog_apply.r' 'catalog_fakerun.r'
 'catalog_index.r' 'catalog_intersect.r' 'catalog_laxindex.r'
 'catalog_makecluster.r' 'catalog_merge_results.R'
 'catalog_retile.r' 'catalog_select.r' 'cloud_metrics.r'
 'clusters_apply.r' 'deprecated.R' 'doc-drivers.R' 'doc-lidR.R'
 'doc-parallelism.R' 'grid_canopy.r' 'grid_density.r'
 'grid_metrics.r' 'grid_terrain.r' 'hexbin_metrics.r'
 'io_readLAS.r' 'io_readLAScatalog.r' 'io_writeANY.r'
 'io_writeLAS.r' 'lascheck.r' 'lasclip.r' 'lasdetectshape.r'
 'lasfilter.r' 'lasfilterdecimate.r' 'lasfilterduplicates.r'
 'lasfiltersurfacepoints.r' 'lasgenerator.R' 'lasground.r'
 'lasidentify.r' 'lasmergelas.r' 'lasmergespatial.r'
 'lasnormalize.r' 'lasrangelocation.R' 'lasrescale.R'
 'lasroi.r' 'lassmooth.r' 'lassnags.r' 'lastransform.r'
 'lastrees.r' 'lasupdateheader.r' 'lasvoxelize.r'
 'methods-LAS.r' 'methods-LAScatalog.r' 'methods-LAScluster.r'
 'methods-LASHeader.r' 'plot.r' 'plot.s3.r' 'point_metrics.R'
 'print.r' 'projection.r' 'sensor_tracking.R' 'tree_detection.r'
 'tree_hulls.r' 'tree_metrics.r' 'utils_assertive.r'
 'utils_catalog_options.r' 'utils_colors.r'
 'utils_define_constant.R' 'utils_delaunay.R' 'utils_geometry.r'
 'utils_is.r' 'utils_metrics.r' 'utils_misc.r' 'utils_raster.r'
 'utils_threads.r' 'utils_typecast.r' 'voxel_metrics.r' 'zzz.r'

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### Description

`lidR` provides a set of tools to manipulate airborne LiDAR data in forestry contexts. The package works essentially with .las or .laz files. The toolbox includes algorithms for DSM, CHM, DTM, ABA, normalisation, tree detection, tree segmentation and other tools, as well as an engine to process wide LiDAR coverages split into many files.
Details

To learn more about lidR, start with the vignettes: browseVignettes(package = "lidR"). Users can also find unofficial supplementary documentation in the github wiki pages. To ask "how to" questions please ask on gis.stackexchange.com with the tag lidr.

Package options

- **lidR.progress** Several functions have a progress bar for long operations (but not all). Should lengthy operations show a progress bar? Default: TRUE
- **lidR.progress.delay** The progress bar appears only for long operations. After how many seconds of computation does the progress bar appear? Default: 2
- **lidR.verbose** Make the package verbose. Default: FALSE
- **lidR.buildVRT** The functions grid_* can write the rasters sequentially on the disk and load back a virtual raster mosaic (VRT) instead of the list of written files. Should a VRT be built? Default: TRUE

Author(s)

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- Florian De Boissieu (Fixed bugs and improved catalog features) [contributor]
- Andrew Sánchez Meador (Implemented wing2015 for lassnags) [contributor]
- Bourdon Jean-François (Implemented sensor_tracking) [contributor]

See Also

Useful links:

- [https://github.com/Jean-Romain/lidR](https://github.com/Jean-Romain/lidR)

area

Surface covered by a LAS* object

Description

Surface covered by a LAS* object. For LAS point clouds it is computed based on the convex hull of the points. For a LAScatalog it is computed as the sum of the bounding boxes of the files. For overlapping tiles the value may be larger than the total covered area because some regions are sampled twice. For a LASheader it is computed with the bounding box. The function npoints does what the user may expect it to do and the function density is equivalent to npoints(x)/area(x). As a consequence for the same file area applied on a LASheader or on a LAS can return slightly different values.
Usage

area(x, ...)

## S4 method for signature 'LAS'
area(x, ...)

## S4 method for signature 'LASheader'
area(x, ...)

## S4 method for signature 'LAScatalog'
area(x, ...)

npoints(x, ...)

## S4 method for signature 'LAS'
npoints(x, ...)

## S4 method for signature 'LASheader'
npoints(x, ...)

## S4 method for signature 'LAScatalog'
npoints(x, ...)

density(x, ...)

## S4 method for signature 'LAS'
density(x, ...)

## S4 method for signature 'LASheader'
density(x, ...)

## S4 method for signature 'LAScatalog'
density(x, ...)

Arguments

x       An object of the class LAS*.
...

Value

numeric. A number. Notice that for area the measure is in the same units as the coordinate reference system.
as.list.LASheader

Transform to a list

Description

Functions to construct, coerce and check for both kinds of R lists.

Usage

```r
## S3 method for class 'LASheader'
as.list(x, ...)
```

Arguments

- `x` A LASHeader object
- `...` unused

as.spatial

Transform a LAS* object into an sp object

Description

LAS and LAScatalog objects are transformed into SpatialPointsDataFrame and SpatialPolygonsDataFrame objects, respectively.

Usage

```r
as.spatial(x)
```

Arguments

- `x` an object from the lidR package

Value

An object from sp
Description

This function gives users access to the LAScatalog processing engine. It allows the application of a user-defined routine over an entire catalog. The LAScatalog processing engine tool is explained in the LAScatalog class.

catalog_apply is the core of the lidR package. It drives every single function that can process a LAScatalog. It is flexible and powerful but also complex. catalog_sapply is the same with the option automerge = TRUE enforced to simplify the output.

Warning: the LAScatalog processing engine has a mechanism to load buffered data 'on-the-fly' to avoid edge artifacts, but no mechanism to remove the buffer after applying user-defined functions, since this task is specific to each process. In other lidR functions this task is performed specifically for each function. In catalog_apply the user’s function can return any output, thus users must take care of this task themselves (See section "Edge artifacts")

Usage

`catalog_apply(ctg, FUN, ..., .options = NULL)`

`catalog_sapply(ctg, FUN, ..., .options = NULL)`

Arguments

- `ctg` A LAScatalog object.
- `FUN` A user-defined function that respects a given template (see section function template)
- `...` Optional arguments to `FUN`.
- `.options` See dedicated section and examples.

Edge artifacts

It is important to take precautions to avoid 'edge artifacts' when processing wall-to-wall tiles. If the points from neighboring tiles are not included during certain processes, this could create 'edge artifacts' at the tile boundaries. For example, empty or incomplete pixels in a rasterization process, or dummy elevations in a ground interpolation. The LAScatalog processing engine provides internal tools to load buffered data 'on-the-fly'. However, there is no mechanism to remove the results computed in the buffered area since this task depends on the output of the user-defined function. The user must take care of this task (see examples) to prevent unexpected output with duplicated entries or conflict between values computed twice.
Buffered data

The LAS objects read by the user function have a special attribute called 'buffer' that indicates, for each point, if it comes from a buffered area or not. Points from non-buffered areas have a 'buffer' value of 0, while points from buffered areas have a 'buffer' value of 1, 2, 3 or 4, where 1 is the bottom buffer and 2, 3 and 4 are the left, top and right buffers, respectively. This allows for filtering of buffer points if required.

Function template

The parameter FUN expects a function with a first argument that will be supplied automatically by the LAScatalog processing engine. This first argument is a LAScluster. A LAScluster is an internal undocumented class but the user needs to know only three things about this class:

- It represents a chunk of the catalog
- The function readLAS can be used with a LAScluster
- The function extent or bbox can be used with a LAScluster and it returns the bounding box of the cluster without the buffer. It can be used to clip the output and remove the buffered region (see examples).

A user-defined function must be templated like this:

```r
def myfun = function(cluster, ...) {
  las = readLAS(cluster)
  if (is.empty(las)) return(NULL)
  # do something
  # remove the buffer of the output
  return(something)
}
```

The line if(is.empty(las)) return(NULL) is important because some clusters (chunks) may contain 0 points (we can't know this before reading the file). In this case an empty point cloud with 0 points is returned by readLAS and this may fail in subsequent code. Thus, exiting early from the user-defined function by returning NULL indicates to the internal engine that the cluster was empty.

.options

Users may have noticed that some lidR functions throw an error when the processing options are inappropriate. For example, some functions need a buffer and thus buffer = 0 is forbidden. Users can add the same constraints to protect against inappropriate options. The .options argument is a list that allows users to tune the behavior of the processing engine.

- drop_null = FALSE Not intended to be used by regular users. The engine does not remove NULL outputs
- need_buffer = TRUE the function complains if the buffer is 0.
- need_output_file = TRUE the function complains if no output file template is provided.
• `raster_alignment = ...` the function checks the alignment of the chunks. This option is important if the output is a raster. See below for more details.

• `automerge = TRUE` by default the engine returns a list with one item per chunk. If `automerge = TRUE`, it tries to merge the outputs into a single object: a `Raster*`, a `Spatial*`, a `LAS*` similar to other functions of the package. This is a fail-safe option so in the worst case, if the merge fails, the list is returned.

When the function `FUN` returns a raster it is important to ensure that the chunks are aligned with the raster to avoid edge artifacts. Indeed, if the edge of a chunk does not correspond to the edge of the pixels, the output will not be strictly continuous and will have edge artifacts (that might not be visible). Users can check this with the options `raster_alignment`, that can take the resolution of the raster as input, as well as the starting point if needed. The following are accepted:

```
# check if chunks are aligned with a raster of resolution 20
raster_alignment = 20
raster_alignment = list(res = 20)

# check if chunks are aligned with a raster of resolution 20
# that starts at (0,10)
raster_alignment = list(res = 20, start = c(0,10))
```

See also `grid_metrics` for more details.

### Supported processing options

Supported processing options for a `LAScatalog` (in bold). For more details see the `LAScatalog` engine documentation:

• `chunk_size`: How much data is loaded at once.
• `chunk_buffer`: Load chunks with a buffer.
• `chunk_alignment`: Align the chunks.
• `progress`: Displays a progress estimate.
• `output_files`: The user-defined function outputs will be written to files instead of being returned into R.
• `laz_compression`: write las or laz files only if the user-defined function returns a `LAS` object.
• `select`: Select only the data of interest to save processing memory.
• `filter`: Read only the points of interest.

### Examples

```
# More examples might be available in the official lidR vignettes or
# on the github wiki <http://jean-romain.github.io/lidR/wiki>
```

```
## Example 1: detect all the tree tops over an entire catalog
## (this is basically a reproduction of the existing lidR function 'tree_detection')
```
# 1. Build the user-defined function that analyzes each chunk of the catalog.
# The function’s first argument is a LAScluster object. The other arguments can be freely
# chosen by the user.
my_tree_detection_method <- function(cluster, ws)
{
    # The cluster argument is a LAScluster object. The user does not need to know how it works.
    # readLAS will load the region of interest (chunk) with a buffer around it, taking advantage of
    # point cloud indexation if possible. The filter and select options are propagated automatically
    las <- readLAS(cluster)
    if (is.empty(las)) return(NULL)

    # Find the tree tops using a user-developed method (here simply a LMF).
    ttops <- tree_detection(las, lmf(ws))

    # ttops is a SpatialPointsDataFrame that contains the tree tops in our region of interest
    # plus the trees tops in the buffered area. We need to remove the buffer otherwise we will get
    # some trees more than once.
    bbox <- raster::extent(cluster)
    ttops <- raster::crop(ttops, bbox)

    return(ttops)
}

# 2. Build a project (here, a single file catalog for the purposes of this dummy example).
LASfile <- system.file("extdata", "MixedConifer.laz", package="lidR")
project <- readLAScatalog(LASfile)
plot(project)

# 3. Set some catalog options.
# For this dummy example, the chunk size is 80 m and the buffer is 10 m
opt_chunk_buffer(project) <- 10
opt_chunk_size(project) <- 80 # small because this is a dummy example.
opt_select(project) <- "xyz" # read only the coordinates.
opt_filter(project) <- "-keep_first" # read only first returns.

# 4. Apply a user-defined function to take advantage of the internal engine
opt <- list(need_buffer = TRUE, # catalog_apply will throw an error if buffer = 0
            automerge = TRUE) # catalog_apply will merge the outputs into a single object
output <- catalog_apply(project, my_tree_detection_method, ws = 5, .options = opt)

spplot(output)

## Example 2: compute a rumple index on surface points

rumple_index_surface = function(cluster, res)
{
    las = readLAS(cluster)
    if (is.empty(las)) return(NULL)
catalog_intersect

Subset a LAScatalog with a Spatial* object

description

Subset a LAScatalog with a Spatial* object to keep only the tiles of interest. Internally, it uses the function intersect from raster with a tweak to make it work with a LAScatalog. It can be used to select tiles of interest that encompass Spatial* objects such as SpatialPoints, SpatialPolygons or SpatialLines.

usage

catalog_intersect(ctg, y)

arguments

ctg     A LAScatalog object

y       Extent, Raster*, SpatialPolygons*, SpatialLines* or SpatialPoints* object

value

A LAScatalog
**Description**

The names of the options and their roles are documented in LAScatalog. The options are used by all the functions that support a LAScatalog as input.

**Usage**

```r
opt_chunk_buffer(ctg)
opt_chunk_buffer(ctg) <- value
opt_chunk_size(ctg)
opt_chunk_size(ctg) <- value
opt_chunk_alignment(ctg)
opt_chunk_alignment(ctg) <- value
opt_cores(ctg)
opt_cores(ctg) <- value
opt_progress(ctg)
opt_progress(ctg) <- value
opt_stop_early(ctg)
opt_stop_early(ctg) <- value
opt_wall_to_wall(ctg)
opt_wall_to_wall(ctg) <- value
opt_output_files(ctg)
opt_output_files(ctg) <- value
opt_laz_compression(ctg)
opt_laz_compression(ctg) <- value
opt_select(ctg)
```
### catalog_retile

**Retile a LAScatalog**

**Description**

Splits or merges files to reshape the original catalog files (.las or .laz) into smaller or larger files. It also enables the addition or removal of a buffer around the tiles. The function first displays the layout of the new tiling pattern and then asks the user to validate the command. Internally, the function reads and writes the clusters defined by the internal processing options of a LAScatalog processing engine. Thus, the function is flexible and enables the user to retile the dataset, retile while adding or removing a buffer (negative buffers are allowed), or optionally to compress the data by retiling without changing the pattern but by changing the format (las/laz).

Note that this function is not actually very useful since lidR manages everything (clipping, processing, buffering, ...) internally using the proper options. Thus, retiling may be useful for working in other software, for example, but not in lidR.

```r
opt_select(ctg) <- value
opt_filter(ctg)
opt_filter(ctg) <- value

**Arguments**

- **ctg**: An object of class LAScatalog
- **value**: An appropriate value depending on the expected input.

**Examples**

```r
LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
ctg = readLAScatalog(LASfile)

plot(ctg, chunk_pattern = TRUE)
opt_chunk_size(ctg) <- 150
plot(ctg, chunk_pattern = TRUE)
opt_chunk_buffer(ctg) <- 10
plot(ctg, chunk_pattern = TRUE)
opt_chunk_alignment(ctg) <- c(270,250)
plot(ctg, chunk_pattern = TRUE)
summary(ctg)

opt_output_files(ctg) <- "/path/to/folder/templated_filename_{XBOTTOM}_{ID}"
summary(ctg)
```

---

```r
catalog_retile
```
Usage

catalog_retile(ctg)

Arguments

ctg A LAScatalog object

Value

A new LAScatalog object

Working with a LAScatalog

This section appears in each function that supports a LAScatalog as input.

In lidR when the input of a function is a LAScatalog the function uses the LAScatalog processing engine. The user can modify the engine options using the available options. A careful reading of the engine documentation is recommended before processing LAScatalogs. Each lidR function should come with a section that documents the supported engine options.

The LAScatalog engine supports .lax files that significantly improve the computation speed of spatial queries using a spatial index. Users should really take advantage a .lax files, but this is not mandatory.

Supported processing options

Supported processing options for a LAScatalog (in bold). For more details see the LAScatalog engine documentation:

- chunk_size: Size of the new tiles.
- buffer: Load new tiles with a buffer. The expected value is usually 0.
- alignment: Alignment of the new tiles.
- cores: The number of cores used. catalog_retile streams the data (nothing is loaded at R level). The maximum number of cores can be safely used.
- progress: Displays a progress estimation.
- output_files*: Mandatory. The new tiles will be written in new files.
- laz_compression: save las or laz files.
- select: catalog_retile preserve the file format anyway.
- filter: Retile and save only the points of interest.
Examples

## Not run:
ctg = readLAScatalog("path/to/catalog")

# Create a new set of .las files 500 x 500 wide in the folder
# path/to/new/catalog/ and iteratively named Forest_1.las, Forest_2.las
# Forest_3.las, and so on.

opt_chunk_buffer(ctg) <- 0
opt_chunk_size(ctg) <- 500
opt_output_files(ctg) <- "path/to/new/catalog/Forest_{ID}
newctg = catalog_retile(ctg)

# Create a new set of .las files equivalent to the original,
# but extended with a 50 m buffer in the folder path/to/new/catalog/
# and iteratively named named after the original files.

opt_chunk_buffer(ctg) <- 50
opt_chunk_size(ctg) <- 0
opt_output_files(ctg) <- "path/to/new/catalog/{ORIGINALFILENAME}_buffered"
nnewctg = catalog_retile(ctg)

# Create a new set of compressed .laz file equivalent to the original, keeping only
# first returns above 2 m

opt_chunk_buffer(ctg) <- 0
opt_chunk_size(ctg) <- 0
opt_laz_compression(ctg) <- TRUE
opt_filter(ctg) <- "-keep_first -drop_z_below 2"
nnewctg = catalog_retile(ctg)

## End(Not run)

catalog_select Select LAS files manually from a LAScatalog

description

Select a set of LAS tiles from a LAScatalog interactively using the mouse. This function allows
users to subset a LAScatalog by clicking on a map of the file.

Usage

catalog_select(
  ctg,
  mapview = TRUE,
  method = c("subset", "flag_unprocessed", "flag_processed")
)
Arguments

c tg A LAScatalog object
mapview logical. If FALSE, use R base plot instead of mapview (no pan, no zoom, see also plot)
method character. By default selecting tiles that are a subset of the catalog. It is also possible to flag the files to maintain the catalog as a whole but process only a subset of its content. flag_unprocessed enables users to point and click on files that will not be processed. flag_processed enables users to point and click on files that will be processed.

Value
A LAScatalog object

Examples

## Not run:
c tg = readLAScatalog("<Path to a folder containing a set of .las files>")
new_ctg = catalog_select(ctg)

## End(Not run)

cloud_metrics
Compute metrics for a cloud of points

Description

cloud_metrics computes a series of user-defined descriptive statistics for a LiDAR dataset. See grid_metrics to compute metrics on a grid. Basically there are no predefined metrics. Users must write their own functions to create metrics (see example). The following existing functions can serve as a guide to help users compute their own metrics:

- stdmetrics
- entropy
- VCI
- LAD

Usage
cloud_metrics(las, func)

Arguments

las An object of class LAS
func formula. An expression to be applied to the point cloud (see example)
**Value**

It returns a list containing the metrics

**See Also**

grid_metrics stdmetrics entropy VCI LAD

Other metrics: grid_metrics(), hexbin_metrics(), point_metrics(), tree_metrics(), voxel_metrics()

**Examples**

```r
LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
lidar = readLAS(LASfile)

cloud_metrics(lidar, ~max(Z))
cloud_metrics(lidar, ~mean(Intensity))

# Define your own new metrics
myMetrics = function(z, i)
{
  metrics = list(
    zwimean = sum(z*i)/sum(i), # Mean elevation weighted by intensities
    zimean = mean(z*i), # Mean products of z by intensity
    zsqmean = sqrt(mean(z^2)) # Quadratic mean
  )

  return(metrics)
}

metrics = cloud_metrics(lidar, ~myMetrics(Z, Intensity))

# Predefined metrics
cloud_metrics(lidar, .stdmetrics)
```

---

**csf**

*Ground Segmentation Algorithm*

**Description**

This function is made to be used in lasground. It implements an algorithm for segmentation of ground points base on a Cloth Simulation Filter. This method is a strict implementation of the CSF algorithm made by Zhang et al. (2016) (see references) that relies on the authors’ original source code written and exposed to R via the the RCSF package.

**Usage**

```r
csf(sloop_smooth = FALSE,
    class_threshold = 0.5,
```

cloth_resolution = 0.5,
rigidness = 1L,
iterations = 500L,
time_step = 0.65
)

Arguments

sloop_smooth logical. When steep slopes exist, set this parameter to TRUE to reduce errors during post-processing.

class_threshold scalar. The distance to the simulated cloth to classify a point cloud into ground and non-ground. The default is 0.5.

cloth_resolution scalar. The distance between particles in the cloth. This is usually set to the average distance of the points in the point cloud. The default value is 0.5.

rigidness integer. The rigidity of the cloth. 1 stands for very soft (to fit rugged terrain), 2 stands for medium, and 3 stands for hard cloth (for flat terrain). The default is 1.

iterations integer. Maximum iterations for simulating cloth. The default value is 500. Usually, there is no need to change this value.

time_step scalar. Time step when simulating the cloth under gravity. The default value is 0.65. Usually, there is no need to change this value. It is suitable for most cases.

References


See Also

Other ground segmentation algorithms: pmf()

Examples

LASfile <- system.file("extdata", "Topography.laz", package="lidR")
las <- readLAS(LASfile, select = "xyzrn")

mycsf <- csf(TRUE, 1, 1, time_step = 1)
las <- lasground(las, mycsf)
plot(las, color = "Classification")
Description

This function is made to be used in lastrees. It implements an algorithm for tree segmentation based on the Dalponte and Coomes (2016) algorithm (see reference). This is a seeds + growing region algorithm. This algorithm exists in the package itcSegment. This version has been written from the paper in C++. Consequently it is hundreds to millions times faster than the original version. Note that this algorithm strictly performs a segmentation, while the original method as implemented in itcSegment and described in the manuscript also performs pre- and post-processing tasks. Here these tasks are expected to be done by the user in separate functions.

Usage

dalponte2016(
  chm,
  treetops,
  th_tree = 2,
  th_seed = 0.45,
  th_cr = 0.55,
  max_cr = 10,
  ID = "treeID"
)

Arguments

<table>
<thead>
<tr>
<th>Name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>chm</td>
<td>RasterLayer. Image of the canopy. Can be computed with grid_canopy or read from an external file.</td>
</tr>
<tr>
<td>treetops</td>
<td>SpatialPointsDataFrame. Can be computed with tree_detection or read from an external shapefile.</td>
</tr>
<tr>
<td>th_tree</td>
<td>numeric. Threshold below which a pixel cannot be a tree. Default is 2.</td>
</tr>
<tr>
<td>th_seed</td>
<td>numeric. Growing threshold 1. See reference in Dalponte et al. 2016. A pixel is added to a region if its height is greater than the tree height multiplied by this value. It should be between 0 and 1. Default is 0.45.</td>
</tr>
<tr>
<td>th_cr</td>
<td>numeric. Growing threshold 2. See reference in Dalponte et al. 2016. A pixel is added to a region if its height is greater than the current mean height of the region multiplied by this value. It should be between 0 and 1. Default is 0.55.</td>
</tr>
<tr>
<td>max_cr</td>
<td>numeric. Maximum value of the crown diameter of a detected tree (in pixels). Default is 10.</td>
</tr>
<tr>
<td>ID</td>
<td>character. If the SpatialPointsDataFrame contains an attribute with the ID for each tree, the name of this attribute. This way, original IDs will be preserved. If there is no such data trees will be numbered sequentially.</td>
</tr>
</tbody>
</table>
Details

Because this algorithm works on a CHM only there is no actual need for a point cloud. Sometimes the user does not even have the point cloud that generated the CHM. lidR is a point cloud-oriented library, which is why this algorithm must be used in lastrees to merge the result with the point cloud. However the user can use this as a stand-alone function like this:

```r
chm = raster("file/to/a/chm/")
ttops = tree_detection(chm, lmf(3))
crowns = dalponte2016(chm, ttops())
```

References


See Also

Other individual tree segmentation algorithms: `li2012()`, `silva2016()`, `watershed()`
Other raster based tree segmentation algorithms: `silva2016()`, `watershed()`

Examples

```r
LASfile <- system.file("extdata", "MixedConifer.laz", package="lidR")
las <- readLAS(LASfile, select = "xyz", filter = "-drop_z_below 0")
col <- pastel.colors(200)

chm <- grid_canopy(las, 0.5, p2r(0.3))
ker <- matrix(1, 3, 3)
chm <- raster::focal(chm, w = ker, fun = mean, na.rm = TRUE)

ttops <- tree_detection(chm, lmf(4, 2))
las <- lastrees(las, dalponte2016(chm, ttops))
plot(las, color = "treeID", colorPalette = col)
```

Description

These functions are provided for compatibility with older versions of lidR only, and may be defunct as soon as the next release.

Usage

```r
lasmetrics(las, func)
grid_metrics3d(...)
gird_hexametrics(...)
```
Arguments

las, func, ... parameters

dsmtin

Digital Surface Model Algorithm

Description

This function is made to be used in grid_canopy. It implements an algorithm for digital surface model computation using a Delaunay triangulation of first returns with a linear interpolation within each triangle.

Usage

dsmtin(max_edge = 0)

Arguments

max_edge numeric. Maximum edge length of a triangle in the Delaunay triangulation. If a triangle has an edge length greater than this value it will be removed to trim dummy interpolation on non-convex areas. If max_edge = 0 no trimming is done (see examples).

See Also

Other digital surface model algorithms: p2r(), pitfree()

Examples

LASfile <- system.file("extdata", "MixedConifer.laz", package="lidR")
las <- readLAS(LASfile)
col <- height.colors(50)

# Basic triangulation and rasterization of first returns
chm <- grid_canopy(las, res = 1, dsmtin())
plot(chm, col = col)

## Not run:
# Potentially complex concave subset of point cloud
x = c(481340, 481340, 481280, 481300, 481280, 481340)
y = c(3812940, 3813000, 3813000, 3812960, 3812940, 3812940)
las2 = lasclipPolygon(las,x,y)
plot(las2)

# Since the TIN interpolation is done within the convex hull of the point cloud
# dummy pixels are interpolated that are strictly correct according to the interpolation method
# used, but meaningless in our CHM
chm <- grid_canopy(las2, res = 0.5, dsmtin())
plot(chm, col = col)
## entropy

*Normalized Shannon diversity index*

### Description

A normalized Shannon vertical complexity index. The Shannon diversity index is a measure for quantifying diversity and is based on the number and frequency of species present. This index, developed by Shannon and Weaver for use in information theory, was successfully transferred to the description of species diversity in biological systems (Shannon 1948). Here it is applied to quantify the diversity and the evenness of an elevational distribution of las points. It makes bins between 0 and the maximum elevation. If there are negative values the function returns NA.

### Usage

```r
test_entropy <- entropy(z, by = 1, zmax = NULL)
```

### Arguments

- **z**: vector of positive z coordinates
- **by**: numeric. The thickness of the layers used (height bin)
- **zmax**: numeric. Used to turn the function entropy to the function VCI.

### Value

A number between 0 and 1

### References


### See Also

- VCI

```r
# Use 'max_edge' to trim dummy triangles
chm = grid_canopy(las2, res = 0.5, dsmtin(max_edge = 3))
plot(chm, col = col)

## End(Not run)
```
Examples

\[
z = \text{runif}(10000, 0, 10)
\]

# expected to be close to 1. The highest diversity is given for a uniform distribution
entropy(z, by = 1)

\[
z = \text{runif}(10000, 9, 10)
\]

# Must be 0. The lowest diversity is given for a unique possibility
entropy(z, by = 1)

\[
z = \text{abs(rnorm}(10000, 10, 1))
\]

# expected to be between 0 and 1.
entropy(z, by = 1)

---

### extent,LAS-method

#### Extent

Description

Returns an Extent object of a LAS*.

Usage

```r
## S4 method for signature 'LAS'
extent(x, ...)
```

```r
## S4 method for signature 'LAScatalog'
extent(x, ...)
```

Arguments

- `x` An object of the class LAS or LAScatalog
- `...` Unused

Value

Extent object from `raster`

See Also

`raster::extent`
**Description**
Computes the gap fraction profile using the method of Bouvier et al. (see reference)

**Usage**
gap_fraction_profile(z, dz = 1, z0 = 2)

**Arguments**
- `z`: vector of positive z coordinates
- `dz`: numeric. The thickness of the layers used (height bin)
- `z0`: numeric. The bottom limit of the profile

**Details**
The function assesses the number of laser points that actually reached the layer z+dz and those that passed through the layer [z, z+dz]. By definition the layer 0 will always return 0 because no returns pass through the ground. Therefore, the layer 0 is removed from the returned results.

**Value**
A data.frame containing the bin elevations (z) and the gap fraction for each bin (gf)

**References**

**See Also**
- LAD

**Examples**
```r
z = c(rnorm(1e4, 25, 6), rgamma(1e3, 1, 8)*6, rgamma(5e2, 5,5)*10)
z = z[z<45 & z>0]
hist(z, n=50)
gapFraction = gap_fraction_profile(z)
plot(gapFraction, type="l", xlab="Elevation", ylab="Gap fraction")```
grid_canopy

Digital Surface Model

Description

Creates a digital surface model (DSM) using several possible algorithms. If the user provides a normalised point cloud, the output is indeed a canopy height model (CHM).

Usage

grid_canopy(las, res, algorithm)

Arguments

las An object of class LAS or LAScatalog.
res numeric. The resolution of the output Raster. Can optionally be a RasterLayer. In that case the RasterLayer is used as the layout.
algorithm function. A function that implements an algorithm to compute a digital surface model. lidR implements p2r, dsmtin, pitfree (see respective documentation and examples).

Value

A RasterLayer containing a numeric value in each cell. If the RasterLayers are written on disk when running the function with a LAScatalog, a virtual raster mosaic is returned (see gdalbuildvrt)

Working with a LAScatalog

This section appears in each function that supports a LAScatalog as input.

In lidR when the input of a function is a LAScatalog the function uses the LAScatalog processing engine. The user can modify the engine options using the available options. A careful reading of the engine documentation is recommended before processing LAScatalogs. Each lidR function should come with a section that documents the supported engine options.

The LAScatalog engine supports .lax files that significantly improve the computation speed of spatial queries using a spatial index. Users should really take advantage a .lax files, but this is not mandatory.

Supported processing options

Supported processing options for a LAScatalog in grid_* functions (in bold). For more details see the LAScatalog engine documentation:
• **chunk size**: How much data is loaded at once. The chunk size may be slightly modified internally to ensure a strict continuous wall-to-wall output even when chunk size is equal to 0 (processing by file).

• **chunk buffer**: This function guarantees a strict continuous wall-to-wall output. The buffer option is not considered.

• **chunk alignment**: Align the processed chunks. The alignment may be slightly modified internally to ensure a strict continuous wall-to-wall output.

• **progress**: Displays a progress estimate.

• **output files**: Return the output in R or write each cluster’s output in a file. Supported templates are `{XLEFT}`, `{XRIGHT}`, `{YBOTTOM}`, `{YTOP}`, `{XCENTER}`, `{YCENTER} {ID}` and, if chunk size is equal to 0 (processing by file), `{ORIGINALFILENAME}`.

• **select**: The grid_* functions usually ‘know’ what should be loaded and this option is not considered. In grid_metrics this option is respected.

• **filter**: Read only the points of interest.

### Examples

```r
LASfile <- system.file("extdata", "MixedConifer.laz", package="lidR")
las <- readLAS(LASfile)
col <- height.colors(50)

# Points-to-raster algorithm with a resolution of 1 meter
chm <- grid_canopy(las, res = 1, p2r())
plot(chm, col = col)

# Points-to-raster algorithm with a resolution of 0.5 meters replacing each
# point by a 20-cm radius circle of 8 points
chm <- grid_canopy(las, res = 0.5, p2r(0.2))
plot(chm, col = col)

# Basic triangulation and rasterization of first returns
chm <- grid_canopy(las, res = 0.5, dsmtin())
plot(chm, col = col)

# Khosravipour et al. pitfree algorithm
chm <- grid_canopy(las, res = 0.5, pitfree(c(0,2,5,10,15), c(0, 1.5)))
plot(chm, col = col)
```

---

**grid_density**

*Map the pulse or point density*

### Description

Creates a map of the point density. If a "pulseID" attribute is found, also returns a map of the pulse density.
Usage

grid_density(las, res = 4)

Arguments

- **las**: An object of class LAS or LAScatalog.
- **res**: numeric. The size of a grid cell in LiDAR data coordinates units. Default is 4 = 16 square meters.

Value

A RasterLayer or a RasterBrick containing a numeric value in each cell. If the RasterLayers are written on disk when running the function with a LAScatalog, a virtual raster mosaic is returned (see gdalbuildvrt)

Working with a LAScatalog

This section appears in each function that supports a LAScatalog as input.

In lidR when the input of a function is a LAScatalog the function uses the LAScatalog processing engine. The user can modify the engine options using the available options. A careful reading of the engine documentation is recommended before processing LAScatalogs. Each lidR function should come with a section that documents the supported engine options.

The LAScatalog engine supports .lax files that significantly improve the computation speed of spatial queries using a spatial index. Users should really take advantage a .lax files, but this is not mandatory.

Supported processing options

Supported processing options for a LAScatalog in grid_* functions (in bold). For more details see the LAScatalog engine documentation:

- **chunk size**: How much data is loaded at once. The chunk size may be slightly modified internally to ensure a strict continuous wall-to-wall output even when chunk size is equal to 0 (processing by file).
- **chunk buffer**: This function guarantees a strict continuous wall-to-wall output. The buffer option is not considered.
- **chunk alignment**: Align the processed chunks. The alignment may be slightly modified internally to ensure a strict continuous wall-to-wall output.
- **progress**: Displays a progress estimate.
- **output files**: Return the output in R or write each cluster’s output in a file. Supported templates are {XLEFT}, {XRIGHT}, {YBOTTOM}, {YTOP}, {XCENTER}, {YCENTER} {ID} and, if chunk size is equal to 0 (processing by file), {ORIGINALFILENAME}.
- **select**: The grid_* functions usually ‘know’ what should be loaded and this option is not considered. In grid_metrics this option is respected.
- **filter**: Read only the points of interest.
Examples

```r
LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
las <- readLAS(LASfile)

d <- grid_density(las, 5)
plot(d)
d <- grid_density(las, 10)
plot(d)

las <- laspulse(las)
d <- grid_density(las)
plot(d)
```

---

**grid_metrics**

**Area-Based Approach**

**Description**

Computes a series of user-defined descriptive statistics for a LiDAR dataset within each pixel of a raster (area-based approach). The grid cell coordinates are pre-determined for a given resolution, so the algorithm will always provide the same coordinates independently of the dataset. When `start = (0,0)` and `res = 20` grid_metrics will produce the following cell centers: (10,10), (10,30), (30,10) etc. aligning the corner of a cell on (0,0). When `start = (-10, -10)` and `res = 20` grid_metrics will produce the following cell centers: (0,0), (0,20), (20,0) etc. aligning the corner of a cell on (-10, -10).

**Usage**

```r
grid_metrics(las, func, res = 20, start = c(0, 0), filter = NULL)
```

**Arguments**

- **las**
  An object of class LAS or LAScatalog.
- **func**
  formula. An expression to be applied to each cell (see section "Parameter func").
- **res**
  numeric. The resolution of the output Raster. Can optionally be a RasterLayer. In that case the RasterLayer is used as the layout.
- **start**
  vector of x and y coordinates for the reference raster. Default is (0,0) meaning that the grid aligns on (0,0).
- **filter**
  formula of logical predicates. Enables the function to run only on points of interest in an optimized way. See examples.

**Value**

A RasterLayer or a RasterBrick containing a numeric value in each cell. If the RasterLayers are written on disk when running the function with a LAScatalog, a virtual raster mosaic is returned (see gdalbuildvrt)
Parameter `func`

The function to be applied to each cell is a classical function (see examples) that returns a labeled list of metrics. For example, the following function `f` is correctly formed.

\[
f = \text{function}(x) \{ \text{list}(\text{mean} = \text{mean}(x), \text{max} = \text{max}(x))\}
\]

And could be applied either on the `Z` coordinates or on the intensities. These two statements are valid:

```r
grid_metrics(las, ~f(Z), res = 20)
grid_metrics(las, ~f(Intensity), res = 20)
```

The following existing functions allow the user to compute some predefined metrics:

- `stdmetrics`
- `entropy`
- `VCI`
- `LAD`

But usually users must write their own functions to create metrics. `grid_metrics` will dispatch the point cloud in the user’s function.

**Working with a LAScatalog**

This section appears in each function that supports a LAScatalog as input.

In `lidR` when the input of a function is a LAScatalog the function uses the LAScatalog processing engine. The user can modify the engine options using the available options. A careful reading of the engine documentation is recommended before processing LAScatalogs. Each `lidR` function should come with a section that documents the supported engine options.

The LAScatalog engine supports `.lax` files that significantly improve the computation speed of spatial queries using a spatial index. Users should really take advantage a `.lax` files, but this is not mandatory.

**Supported processing options**

Supported processing options for a LAScatalog in `grid_*` functions (in bold). For more details see the LAScatalog engine documentation:

- **chunk size**: How much data is loaded at once. The chunk size may be slightly modified internally to ensure a strict continuous wall-to-wall output even when chunk size is equal to 0 (processing by file).
- **chunk buffer**: This function guarantees a strict continuous wall-to-wall output. The buffer option is not considered.
- **chunk alignment**: Align the processed chunks. The alignment may be slightly modified internally to ensure a strict continuous wall-to-wall output.
• **progress**: Displays a progress estimate.

• **output files**: Return the output in R or write each cluster’s output in a file. Supported templates are `{XLEFT}`, `{XRIGHT}`, `{YBOTTOM}`, `{YTOP}`, `{XCENTER}`, `{YCENTER}` `{ID}` and, if chunk size is equal to 0 (processing by file), `{ORIGINALFILENAME}`.

• **select**: The grid_* functions usually 'know' what should be loaded and this option is not considered. In grid_metrics this option is respected.

• **filter**: Read only the points of interest.

See Also

Other metrics: `cloud_metrics()`, `hexbin_metrics()`, `point_metrics()`, `tree_metrics()`, `voxel_metrics()`

Examples

```r
LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
las = readLAS(LASfile)
col = height.colors(50)

# === Using all points ===

# Canopy surface model with 4 m^2 cells
metrics = grid_metrics(las, ~max(Z), 2)
plot(metrics, col = col)

# Mean height with 400 m^2 cells
metrics = grid_metrics(las, ~mean(Z), 20)
plot(metrics, col = col)

# Define your own new metrics
myMetrics = function(z, i) {
  metrics = list(  
    zwimean = sum(z*i)/sum(i), # Mean elevation weighted by intensities  
    zimean = mean(z*i), # Mean products of z by intensity  
    zsqmean = sqrt(mean(z^2))) # Quadratic mean

  return(metrics)
}

metrics = grid_metrics(las, ~myMetrics(Z, Intensity))

plot(metrics, col = col)
plot(metrics, "zwimean", col = col)
plot(metrics, "zimean", col = col)

# === With point filters ===

# Compute using only some points: basic
first = lasfilter(las, ReturnNumber == 1)
metrics = grid_metrics(first, ~mean(Z), 20)

# Compute using only some points: optimized
```


# faster and uses less memory. No intermediate object
metrics = grid_metrics(las, ~mean(Z), 20, filter = ~ReturnNumber == 1)

# Compute using only some points: best
# ~50% faster and uses ~10x less memory
las = readLAS(LASfile, filter = "~keep_first")
metrics = grid_metrics(las, ~mean(Z), 20)

grid_terrain

Digital Terrain Model

Description

Interpolates the ground points and creates a rasterized digital terrain model. The algorithm uses
the points classified as "ground" (Classification = 2 according to LAS file format specifications) to
compute the interpolation.
How well the edges of the dataset are interpolated depends on the interpolation method used. Thus,
a buffer around the region of interest is always recommended to avoid edge effects.

Usage

grid_terrain(
    las,
    res = 1,
    algorithm,
    keep_lowest = FALSE,
    full_raster = FALSE,
    use_class = c(2L, 9L)
)

Arguments

las An object of class LAS or LAScatalog.
res numeric. The resolution of the output Raster. Can optionally be a RasterLayer. In that case the RasterLayer is used as the layout.
algorithm function. A function that implements an algorithm to compute spatial interpola-
tion. lidR implements knnidw, tin, and kriging (see respective documentation and examples).
keep_lowest logical. This option forces the original lowest ground point of each cell (if it exists) to be chosen instead of the interpolated values.
full_raster logical. By default the interpolation is made only within the convex hull of the point cloud. This prevent against meaningless interpolations where there is no data. If TRUE each pixel of the raster is interpolated.
use_class integer vector. By default the terrain is computed by using ground points (class 2) and water points (class 9).
Value

A RasterLayer containing a numeric value in each cell. If the RasterLayers are written on disk when running the function with a LAScatalog, a virtual raster mosaic is returned (see `gdalbuildvrt`).

Working with a LAScatalog

This section appears in each function that supports a LAScatalog as input.

In `lidR` when the input of a function is a LAScatalog the function uses the LAScatalog processing engine. The user can modify the engine options using the available options. A careful reading of the engine documentation is recommended before processing LAScatalogs. Each `lidR` function should come with a section that documents the supported engine options.

The LAScatalog engine supports .lax files that significantly improve the computation speed of spatial queries using a spatial index. Users should really take advantage a .lax files, but this is not mandatory.

Supported processing options

Supported processing options for a LAScatalog in grid_* functions (in bold). For more details see the LAScatalog engine documentation:

- **chunk size**: How much data is loaded at once. The chunk size may be slightly modified internally to ensure a strict continuous wall-to-wall output even when chunk size is equal to 0 (processing by file).
- **chunk buffer**: This function guarantees a strict continuous wall-to-wall output. The buffer option is not considered.
- **chunk alignment**: Align the processed chunks. The alignment may be slightly modified internally to ensure a strict continuous wall-to-wall output.
- **progress**: Displays a progress estimate.
- **output files**: Return the output in R or write each cluster’s output in a file. Supported templates are `{XLEFT}`, `{XRIGHT}`, `{YBOTTOM}`, `{YTOP}`, `{XCENTER}`, `{YCENTER}` `{ID}` and, if chunk size is equal to 0 (processing by file), `{ORIGINALFILENAME}`.
- **select**: The grid_* functions usually 'know' what should be loaded and this option is not considered. In grid_metrics this option is respected.
- **filter**: Read only the points of interest.

See Also

`lasnormalize`

Examples

```r
LASfile <- system.file("extdata", "Topography.laz", package="lidR")
las = readLAS(LASfile)
```
plot(las)

dtm1 = grid_terrain(las, algorithm = knnidw(k = 6L, p = 2))
dtm2 = grid_terrain(las, algorithm = tin())
dtm3 = grid_terrain(las, algorithm = kriging(k = 10L))

## Not run:
plot(dtm1)
plot(dtm2)
plot(dtm3)
plot_dtm3d(dtm1)
plot_dtm3d(dtm2)
plot_dtm3d(dtm3)

## End(Not run)

---

**hexbin_metrics**  
*Area-Based Approach in hexagonal cells.*

**Description**

Computes a series of descriptive statistics for a LiDAR dataset within hexagonal cells. This function is identical to `grid_metrics` but with hexagonal cells instead of square pixels. After all, we conduct circular plot inventories and we map models on pixel-based maps. `hexbin_metrics` provides the opportunity to test something else. Refer to `grid_metrics` for more information.

**Usage**

```r
hexbin_metrics(las, func, res = 20)
```

**Arguments**

- **las**  
  An object of class `LAS`.

- **func**  
  formula. An expression to be applied to each hexagonal cell.

- **res**  
  numeric. To be consistent with `grid_metrics`, the square of `res` give the area of the hexagonal cells, like in `grid_metrics`. The difference being the fact that for square pixels this is obvious. Here `res = 20` gives 400-square-meter hexagonal cells.

**Value**

A `hexbin` object from package hexbin or a list of `hexbin` objects if several metrics are returned.

**See Also**

Other metrics: `cloud_metrics()`, `grid_metrics()`, `point_metrics()`, `tree_metrics()`, `voxel_metrics()`
**Examples**

```r
LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
lidar = readLAS(LASfile)

col = grDevices::colorRampPalette(c("blue", "cyan2", "yellow", "red"))

# Maximum elevation with a resolution of 8 m
hm = hexbin_metrics(lidar, ~max(Z), 8)
hexbin::plot(hm, colramp = col, main = "Max Z")

# Mean height with a resolution of 20 m
hm = hexbin_metrics(lidar, ~mean(Z), 20)
hexbin::plot(hm, colramp = col, main = "Mean Z")

# Define your own new metrics
myMetrics = function(z, i)
{
  metrics = list(
    zwimean = sum(z*i)/sum(i), # Mean elevation weighted by intensities
    zimean = mean(z*i), # Mean products of z by intensity
    zsqmean = sqrt(mean(z^2)) # Quadratic mean
  )

  return(metrics)
}

metrics = hexbin_metrics(lidar, ~myMetrics(Z, Intensity), 10)
hexbin::plot(metrics$zwimean, colramp = col, main = "zwimean")
hexbin::plot(metrics$zimean, colramp = col, main = "zimean")
hexbin::plot(metrics$zsqmean, colramp = col, main = "zsqmean")
```

---

**highest**

**Point Cloud Decimation Algorithm**

**Description**

This function is made to be used in `lasfilterdecimate`. It implements an algorithm that creates a grid with a given resolution and filters the point cloud by selecting the highest point within each cell.

**Usage**

`highest(res = 1)`

**Arguments**

- `res` numeric. The resolution of the grid used to filter the point cloud
homogenize

See Also

Other point cloud decimation algorithms: homogenize(), random()

Examples

LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
las = readLAS(LASfile, select = "xyz")

# Select the highest point within each cell of an overlayed grid
thinned = lasfilterdecimate(las, highest(4))
plot(thinned)

---

homogenize  | Point Cloud Decimation Algorithm

Description

This function is made to be used in lasfilterdecimate. It implements an algorithm that creates a grid
with a given resolution and filters the point cloud by randomly selecting some points in each cell. It
is designed to produce point clouds that have uniform densities throughout the coverage area. For
each cell, the proportion of points or pulses that will be retained is computed using the actual local
density and the desired density. If the desired density is greater than the actual density it returns
an unchanged set of points (it cannot increase the density). The cell size must be large enough to
compute a coherent local density. For example in a 2 points/m^2 point cloud, 25 square meters
would be feasible; however 1 square meter cells would not be feasible because density does not
have meaning at this scale.

Usage

homogenize(density, res = 5, use_pulse = FALSE)

Arguments

density  | numeric. The desired output density.
res      | numeric. The resolution of the grid used to filter the point cloud
use_pulse | logical. Decimate by removing random pulses instead of random points (requires running laspulse first)

See Also

Other point cloud decimation algorithms: highest(), random()
### Examples

```r
LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
las = readLAS(LASfile, select = "xyz")

# Select points randomly to reach an homogeneous density of 1
thinned = lasfilterdecimate(las, homogenize(1,5))
plot(grid_density(thinned))
```

### is

* A set of boolean tests on objects

### Description

- `is.empty` tests if a LAS object is a point cloud with 0 points.
- `is.overlapping` tests if a LAScatalog has overlapping tiles.
- `is.indexed` tests if the points of a LAScatalog are indexed with .lax files.
- `is.algorithm` tests if an object is an algorithm of the lidR package.
- `is.parallelised` tests if an algorithm of the lidR package is natively parallelised with OpenMP.

Returns TRUE if the algorithm is at least partially parallelised i.e. if some portion of the code is computed in parallel.

### Usage

```r
is.empty(las)

is.overlapping(catalog)

is.indexed(catalog)

is.algorithm(x)

is.parallelised(algorithm)
```

### Arguments

- `las` A LAS object.
- `catalog` A LAScatalog object.
- `x` Any R object.
- `algorithm` An algorithm object.

### Value

TRUE or FALSE
knnidw

Spatial Interpolation Algorithm

Description

This function is made to be used in grid_terrain or lasnormalize. It implements an algorithm for spatial interpolation. Interpolation is done using a k-nearest neighbour (KNN) approach with an inverse-distance weighting (IDW).

Usage

knnidw(k = 10, p = 2)

Arguments

k numeric. Number of k-nearest neighbours. Default 10.

See Also

Other spatial interpolation algorithms: kriging(), tin()

Examples

LASfile <- system.file("extdata", "Topography.laz", package="lidR")
las = readLAS(LASfile)
# plot(las)
dtm = grid_terrain(las, algorithm = knnidw(k = 6L, p = 2))
plot(dtm, col = terrain.colors(50))
plot_dtm3d(dtm)
**kriging**  

*Spatial Interpolation Algorithm*

**Description**

This function is made to be used in `gridTerrain` or `lasground`. It implements an algorithm for spatial interpolation. Spatial interpolation is based on universal kriging using the `krige` function from `gstat`. This method combines the KNN approach with the kriging approach. For each point of interest it kriges the terrain using the k-nearest neighbour ground points. This method is more difficult to manipulate but it is also the most advanced method for interpolating spatial data.

**Usage**

```r
kriging(model = gstat::vgm(0.59, "Sph", 874), k = 10L)
```

**Arguments**

- `model` A variogram model computed with `vgm`. If NULL it performs an ordinary or weighted least squares prediction.

**See Also**

Other spatial interpolation algorithms: `knnidw`, `tin`

**Examples**

```r
LASfile <- system.file("extdata", "Topography.laz", package="lidR")
las = readLAS(LASfile)

# plot(las)
dtm = gridTerrain(las, algorithm = kriging())
plot(dtm, col = terrain.colors(50))
plot_dtm3d(dtm)
```

---

**LAD**  

*Leaf area density*

**Description**

Computes a leaf area density profile based on the method of Bouvier et al. (see reference)

**Usage**

```r
LAD(z, dz = 1, k = 0.5, z0 = 2)
```
Arguments

- **z**: vector of positive z coordinates
- **dz**: numeric. The thickness of the layers used (height bin)
- **k**: numeric. is the extinction coefficient
- **z0**: numeric. The bottom limit of the profile

Details

The function assesses the number of laser points that actually reached the layer \( z + dz \) and those that passed through the layer \([z, z+dz]\) (see gap_fraction_profile). Then it computes the log of this quantity and divides it by the extinction coefficient \( k \) as described in Bouvier et al. By definition the layer 0 will always return infinity because no returns pass through the ground. Therefore, the layer 0 is removed from the returned results.

Value

A data.frame containing the bin elevations (\( z \)) and leaf area density for each bin (lad)

References


See Also

gap_fraction_profile

Examples

```r
z = c(rnorm(1e4, 25, 6), rgamma(1e3, 1, 8)*6, rgamma(5e2, 5,5)*10)
z = z[z<45 & z>0]
lad = LAD(z)
plot(lad, type="l", xlab="Elevation", ylab="Leaf area density")
```

LAS-class

An S4 class to represent a .las or .laz file

Description

Class LAS is the representation of a las/laz file according to the LAS file format specifications.

Usage

```r
LAS(data, header = list(), proj4string = sp::CRS(), check = TRUE)
```
**Arguments**

- **data**: a `data.table` containing the data of a las or laz file.
- **header**: a list or a `LASHeader` containing the header of a las or laz file.
- **proj4string**: projection string of class `CRS-class`.
- **check**: logical. Conformity tests while building the object.

**Details**

A LAS object inherits a `Spatial` object from `sp`. Thus it is a `Spatial` object plus a `data.table` with the data read from a las/laz file and a `LASHeader` (see the ASPRS documentation for the LAS file format for more information). Because las files are standardized the table of attributes read from the las/laz file is also standardized. Columns are named:

- `X` (numeric)
- `Y` (numeric)
- `Z` (numeric)
- `Intensity` (integer)
- `ReturnNumber` (integer)
- `NumberOfReturns` (integer)
- `ScanDirectionFlag` (integer)
- `EdgeOfFlightline` (integer)
- `Classification` (integer)
- `Synthetic_flag` (logical)
- `Keypoint_flag` (logical)
- `Withheld_flag` (logical)
- `ScanAngle` (integer)
- `UserData` (integer)
- `PointSourceID` (integer)

**Value**

An object of class `LAS`

**Functions**

- **LAS**: creates objects of class `LAS`. The original data is updated by reference to clamp the coordinates with respect to the scale factor of the header. If header is not provided scale factor is set to 0.001.

**Slots**

- `bbox`: Object of class `matrix`, with bounding box
- `proj4string`: Object of class `CRS`, projection string
- `data`: Object of class `data.table`. Point cloud data according to the LAS file format
- `header`: Object of class `LASHeader`. las file header according to the LAS file format
lasaddattribute

Add attributes into a LAS object

Description

A LAS object represents a .las file in R. According to the LAS specifications a las file contains a core of defined attributes, such as XYZ coordinates, intensity, return number, and so on for each point. It is possible to add supplementary attributes. The functions lasadd* enable the user to add new attributes (see details).

Usage

lasadddata(las, x, name)

lasaddextrabytes(las, x, name, desc)

lasaddextrabytes_manual(
    las,
    x,
    name,
    desc,
    type,
    offset = NULL,
)
scale = NULL,
    NA_value = NULL
)

lasremoveextrabytes(las, name)

Arguments

las An object of class LAS
x a vector that needs to be added in the LAS object. For lasaddextrabytes* it can be missing (see details).
name character. The name of the extra bytes attribute to add in the file.
desc character. A short description of the extra bytes attribute to add in the file (32 characters).
type character. The data type of the extra bytes attribute. Can be "uchar", "char", "ushort", "short", "uint", "int", "uint64", "int64", "float", "double".
scale, offset numeric. The scale and offset of the data. NULL if not relevant.
NA_value numeric or integer. NA is not a valid value in a las file. At time of writing it will be replaced by this value that will be considered as NA. NULL if not relevant.

Details

Users cannot assign names that are the same as the names of the core attributes. These functions are dedicated to adding data not part of the LAS specification. For example, lasaddextrabytes(las, x, "R") will fail because R is a name reserved for the red channel of las file that contains RGB attributes.

lasadddata simply adds a new column in the data but does not update the header. Thus the LAS object is not strictly valid. These data will be temporarily usable at the R level but will not be written in a las file with writeLAS.

lasaddextrabytes does the same as lasadddata but automatically updates the header of the LAS object. Thus, the LAS object is valid and the new data is considered as "extra bytes". This new data will be written in a las file with writeLAS.

lasaddextrabytes_manual allows the user to manually write all the extra bytes metadata. This function is reserved for experienced users with a good knowledge of the LAS specifications. The function does not perform tests to check the validity of the information.

When using lasaddextrabytes and lasaddextrabytes_manual, x can only be of type numeric (integer or double). It cannot be of types character or logical as these are not supported by the las specifications. The types that are supported in lidR are types 0 to 10 (table 24 page 25 of the specification). Types greater than 10 are not supported.

Value

An object of class LAS
Examples

```r
LASfile <- system.file("extdata", "example.laz", package="rlas")
las <- readLAS(LASfile, select = "xyz")

print(las)
print(las@header)

x <- 1:30

las <- lasadddata(las, x, "mydata")
print(las)  # The las object has a new attribute called "mydata"
print(las@header)  # But the header has not been updated. This new data will not be written

las <- lasadddextrabytes(las, x, "mydata2", "A new data")
print(las)  # The las object has a new attribute called "mydata2"
print(las@header)  # The header has been updated. This new data will be written

# Optionally if the data is already in the LAS object you can update the header skipping the
# parameter x
las <- lasadddextrabytes(las, name = "mydata", desc = "Amplitude")
print(las@header)

# Remove an extra bytes attribute
las <- lasremoveextrabytes(las, "mydata2")
print(las)
print(las@header)

las <- lasremoveextrabytes(las, "mydata")
print(las)
print(las@header)
```

LAScatalog-class

An S4 class to represent a catalog of .las or .laz files

Description

A LAScatalog object is a representation of a set of las/laz files. A LAScatalog is a way to manage and process an entire dataset. It allows the user to process a large area, or to selectively clip data from a large area without loading all the data into computer memory. A LAScatalog can be built with the function `readLASCatalog` and is formally an extension of a SpatialPolygonsDataFrame containing extra data to allow users greater control over how the dataset is processed (see details).

Details

A LAScatalog is formally a SpatialPolygonsDataFrame extended with new slots that contain processing options. In lidR, each function that supports a LAScatalog as input will respect these processing options. Internally, processing a catalog is almost always the same and relies on just a few steps:
1. Define chunks. A chunk is an arbitrarily-defined region of interest (ROI) of the catalog. Altogether, the chunks are a wall-to-wall set of ROIs that encompass the whole dataset.

2. Loop over each chunk (in parallel or not).

3. For each chunk, load the points inside the ROI into R, run some R functions, return the expected output.

4. Merge the outputs of the different chunks once they are all processed to build a continuous (wall-to-wall) output.

So basically, a LAScatalog is an object that allows for batch processing but with the specificity that lidR does not loop through las files, but loops seamlessly through chunks that do not necessarily match with the file pattern. This way lidR can sequentially process tiny ROIs even if each file may be individually too big to fit in memory. This is also why point cloud indexation with lax files may significantly speed-up the processing.

It is important to note that catalogs with files that overlap each other are not natively supported by lidR. When encountering such datasets the user should always filter any overlaps if possible. This is possible if the overlapping points are flagged, for example in the 'withheld' attribute. Otherwise lidR will not be able to process the dataset correctly.

**Slots**

- **processing_options** list. A list that contains some settings describing how the catalog will be processed (see dedicated section).

- **chunk_options** list. A list that contains some settings describing how the catalog will be subdivided into chunks to be processed (see dedicated section).

- **output_options** list. A list that contains some settings describing how the catalog will return the outputs (see dedicated section).

- **input_options** list. A list of parameters to pass to readLAS (see dedicated section).

**Processing options**

The slot @processing_options contains a list of options that determine how chunks (the sub-areas that are sequentially processed) are processed.

- **progress**: boolean. Display a progress bar and a chart of progress. Default is TRUE. Progress estimation can be enhanced by installing the package progress. See opt_progress.

- **stop_early**: boolean. Stop the processing if an error occurs in a chunk. If FALSE the process can run until the end removing chunks that failed. Default is TRUE and the user should have no reason to change this. See opt_stop_early.

- **wall.to.wall** logical. The catalog processing engine always guarantees to return a continuous output without edge effects, assuming that the catalog is a wall-to-wall catalog. To do so, some options are checked internally to guard against bad settings, such as buffer = 0 for an algorithm that requires a buffer. In rare cases it might be useful to disable these controls. If wall.to.wall = FALSE controls are disabled and wall-to-wall outputs cannot be guaranteed. See opt_wall_to_wall
Chunk options

The slot @clustering_options contains a list of options that determine how chunks (the sub-areas that are sequentially processed) are made.

- **chunk_size**: numeric. The size of the chunks that will be sequentially processed. A small size allows small amounts of data to be loaded at once, saving computer memory, and vice versa. The computation is usually faster but uses much more memory. If chunk_size = 0 the catalog is processed sequentially by file i.e. a chunk is a file. Default is 0 i.e. by default the processing engine respects the existing tiling pattern. See opt_chunk_size.

- **buffer**: numeric. Each chunk can be read with an extra buffer around it to ensure there is no edge effect between two independent chunks and that the output is continuous. This is mandatory for some algorithms. Default is 30. See opt_chunk_buffer.

- **alignment**: numeric. A vector of size 2 (x and y coordinates, respectively) to align the chunk pattern. By default the alignment is made along (0,0), meaning that the edge of the first chunk will belong on x = 0 and y = 0 and all the the other chunks will be multiples of the chunk size. Not relevant if chunk_size = 0. See opt_chunk_alignment.

Output options

The slot @output_options contains a list of options that determine how clusters (the sub-areas that are sequentially processed) are written. By "written" we mean written to files or written in R memory.

- **output_files**: string. If output_files = "" outputs are returned in R. Otherwise, if output_files is a string the outputs will be written to files. This is useful if the output is too big to be returned in R. A path to a templated filename without extension (the engine guesses it for you) is expected. When several files are going to be written a single string is provided with a template that is automatically filled. For example, the following file names are possible:

  "/home/user/als/normalized/file_{ID}_segmented"
  "C:/user/document/als/zone52_{XLEFT}_{YBOTTOM}_confidential"
  "C:/user/document/als/{ORIGINALFILNAME}_normalized"

  This option will generate as many filenames as needed with custom names for each file. The list of allowed templates is described in the documentation for each function. See opt_output_files.

- **drivers**: list. This contains all the drivers required to seamlessly write Raster*, Spatial*, LAS objects. It is recommended that only advanced users change this option. A dedicated page describes the drivers in lidR-LAScatalog-drivers.

Input options

The slot @input_options contains a list of options that are passed to the function readLAS. Indeed, the readLAS function is not called directly by the user but by the internal processing engine. Users can propagate these options through the LAStool settings.

- **select**: string. The select option. Usually this option is not respected because each function knows which data must be loaded or not. This is documented in each function. See opt_select.

- **filter**: string. The filter option. See opt_filter.
Examples

```r
## Not run:
# Build a catalog
ctg <- readLAScatalog("folder/to/las/files/")

# Set some options
opt_filter(ctg) <- "--keep_first"

# Summary gives a summary of how the catalog will be processed
summary(ctg)

# We can seamlessly use lidR functions
hmean <- grid_metrics(ctg, mean(Z), 20)
ttops <- tree_detection(ctg, lmf(5))

# For low memory config it is probably advisable not to load entire files
# and process chunks instead
opt_chunk_size(ctg) <- 500

# Sometimes the output is likely to be very large
# e.g. large coverage and small resolution
dtm <- grid_terrain(ctg, 1, tin())

# In that case it is advisable to write the output(s) to files
opt_output_files(ctg) <- "path/to/folder/DTM_chunk_{XLEFT}_{YBOTTOM}"

# Raster will be written to disk. The list of written files is returned
# or, in this specific case, a virtual raster mosaic.
dtm <- grid_terrain(ctg, 1, tin())

# When chunks are files the original names of the las files can be preserved
opt_chunk_size(ctg) <- 0
opt_output_files(ctg) <- "path/to/folder/DTM_{ORIGINALFILENAME}"
dtm <- grid_terrain(ctg, 1, tin())

# For some functions, files MUST be written to disk. Indeed, it is certain that R cannot
# handle the entire output.
op_chunk_size(ctg) <- 0
opt_output_files(ctg) <- "path/to/folder/{ORIGINALFILENAME}_norm"
new_ctg <- lasnormalize(ctg, tin())

# The user has access to the catalog engine through the function catalog_apply
output <- catalog_apply(ctg, FUN, ...)

## End(Not run)
```

---

**lascheck**

*Inspect a LAS object*
Description

Performs a deep inspection of a LAS or LAScatalog object and prints a report.

For a LAS object it checks:

- if the point cloud is valid according to las specification
- if the header is valid according to las specification
- if the point cloud is in accordance with the header
- if the point cloud has duplicated points and degenerated ground points
- if the coordinate reference sytem is correctly recorded
- if some pre-processing, such as normalization or ground filtering, is already done.

For a LAScatalog object it checks:

- if the headers are consistent across files
- if the files are overlapping
- if some pre-processing, such as normalization, is already done.

For the pre-processing tests the function only makes an estimation and may not be correct.

Usage

lascheck(las)

Arguments

las

An object of class LAS or LAScatalog.

Examples

LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
las = readLAS(LASfile)
lascheck(las)

Description

Clip LiDAR points within a given geometry from a point cloud (LAS object) or a catalog (LAScatalog object). With a LAS object, the user first reads and loads a point-cloud into memory and then can clip it to get a subset within a region of interest (ROI). With a LAScatalog object, the user can extract any arbitrary ROI for a set of las/laz files, loading only the points of interest. This is faster, easier and much more memory-efficient for extracting ROIs.
Usage

\texttt{lasclip(las, geometry, ...)}

\texttt{lasclipRectangle(las, xleft, ybottom, xright, ytop, ...)}

\texttt{lasclipPolygon(las, xpoly, ypoly, ...)}

\texttt{lasclipCircle(las, xcenter, ycenter, radius, ...)}

Arguments

\begin{itemize}
  \item \texttt{las} An object of class \texttt{LAS} or \texttt{LAScatalog}.
  \item \texttt{geometry} a geometric object. Many types are supported, see section 'supported geometries'.
  \item \ldots in \texttt{lasclip}: optional supplementary options (see supported geometries). Unused in other functions
  \item \texttt{xleft} numeric. left x coordinates of rectangles.
  \item \texttt{ybottom} numeric. bottom y coordinates of rectangles.
  \item \texttt{xright} numeric. right x coordinates of rectangles.
  \item \texttt{ytop} numeric. top y coordinates of rectangles.
  \item \texttt{xpoly} numeric. x coordinates of a polygon.
  \item \texttt{ypoly} numeric. y coordinates of a polygon.
  \item \texttt{xcenter} numeric. x coordinates of discs centers.
  \item \texttt{ycenter} numeric. y coordinates of discs centers.
  \item \texttt{radius} numeric. disc radius or radii.
\end{itemize}

Value

If the input is a \texttt{LAS} object: an object of class \texttt{LAS} or a list of \texttt{LAS} objects if the query implies several regions of interest will be returned.

If the input is a \texttt{LAScatalog} object: an object of class \texttt{LAS}, or a list of \texttt{LAS} objects if the query implies several regions of interest will be returned, or a \texttt{LAScatalog} if the queries are immediately written into files without loading anything in R.

Supported geometries

- \texttt{WKT string}: describing a \texttt{POINT}, a \texttt{POLYGON} or a \texttt{MULTIPOLYGON}. If points a parameter 'radius' must be passed in \ldots
- \texttt{Polygon} or \texttt{Polygons}
- \texttt{SpatialPolygons} or \texttt{SpatialPolygonsDataFrame}
- \texttt{SpatialPoints} or \texttt{SpatialPointsDataFrame} in that case a parameter 'radius' must be passed in \ldots
• SimpleFeature that consistently contains POINT or POLYGON/MULTIPOLYGON. In case of POINT a parameter ‘radius’ must be passed in . . .

• Extent

• matrix 2 x 2 describing a bounding box following this order:

\[
\begin{array}{cc}
\text{min} & \text{max} \\
x & 684816 & 684943 \\
y & 5017823 & 5017957
\end{array}
\]

**Working with a LAScatalog**

This section appears in each function that supports a LAScatalog as input.

In lidR when the input of a function is a LAScatalog the function uses the LAScatalog processing engine. The user can modify the engine options using the available options. A careful reading of the engine documentation is recommended before processing LAScatalogs. Each lidR function should come with a section that documents the supported engine options.

The LAScatalog engine supports .lax files that significantly improve the computation speed of spatial queries using a spatial index. Users should really take advantage a .lax files, but this is not mandatory.

**Supported processing options**

Supported processing options for a LAScatalog (in bold). For more details see the LAScatalog engine documentation:

• chunk_size: Does not make sense here.

• buffer: Not supported yet.

• alignment: Does not makes sense here.

• progress: Displays a progress estimation.

• stop_early: Leave this ‘as-is’ unless you are an advanced user.

• output_files: If ‘output_files’ is set in the catalog, the ROIs will not be returned in R. They will be written immediately in files. See LAScatalog-class and examples. The allowed templates in lasclip are {XLEFT},{XRIGHT},{YBOTTOM},{YTOP},{ID},{XCENTER},{YCENTER} or any names from the table of attributes of a spatial object given as input such as {PLOT_ID} or {YEAR}, for example, if these attributes exist. If empty everything is returned into R.

• laz_compression: write las or laz files

• drivers: Leave this ’as-is’ unless you are an advanced user.

• select: The function will write files equivalent to the originals. This option is not respected.

• filter: Read only the points of interest.
Examples

LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")

# Load the file and clip the region of interest
las = readLAS(LASfile)
subset1 = lasclipRectangle(las, 684850, 5017850, 684900, 5017900)

# Do not load the file(s), extract only the region of interest
# from a bigger dataset
ctg = readLAScatalog(LASfile)
subset2 = lasclipRectangle(ctg, 684850, 5017850, 684900, 5017900)

# Extract all the polygons from a shapefile
shapefile_dir <- system.file("extdata", package = "lidR")
lakes = shapefile(paste0(shapefile_dir, "/lake_polygons_UTM17.shp"))
subset3 = lasclip(ctg, lakes)

# Extract the polygons, write them in files named after the lake names,
# do not load anything in R
opt_output_files(ctg) <- paste0(tempfile(), ","{LAKENAME_1}"
new_ctg = lasclip(ctg, lakes)

## Not run:
plot(subset1)
plot(subset2)
plot(subset3)

## End(Not run)

---

**lasdetectshape**

*Estimation of the shape of the points neighborhood*

Description

Computes the eigenvalues of the covariance matrix of the neighbouring points using several possible algorithms. The points that meet a given criterion based on the eigenvalue are labeled as approximately coplanar/colinear or any other shape supported.

Usage

`lasdetectshape(las, algorithm, attribute = "Shape", filter = NULL)`

Arguments

- **las**: an object of class LAS
- **algorithm**: An algorithm for shape detection. lidR has: `shp_plane`, `shp_hplane` and `shp_line`.
- **attribute**: character. The name of the new column to add into the LAS object.
- **filter**: formula of logical predicates. Enables the function to run only on points of interest in an optimized way. See also examples.
lasfilter

Return points with matching conditions

Description

Return points with matching conditions

Usage

lasfilter(las, ...)

Arguments

las An object of class LAS
...

Logical predicates. Multiple conditions are combined with ‘&’ or ‘,’

Value

An object of class LAS

See Also

Other lasfilters: lasfilterduplicates(), lasfiltersurfacepoints(), lasfilters
Examples

```r
LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
lidar = readLAS(LASfile)

# Select the first returns classified as ground
firstground = lasfilter(lidar, Classification == 2L & ReturnNumber == 1L)

# Multiple arguments are equivalent to &
firstground = lasfilter(lidar, Classification == 2L, ReturnNumber == 1L)

# Multiple criteria
first_or_ground = lasfilter(lidar, Classification == 2L | ReturnNumber == 1L)
```

---

**lasfilterdecimate**

*Decimate a LAS object*

Description

Reduce the number of points using several possible algorithms.

Usage

```r
lasfilterdecimate(las, algorithm)
```

Arguments

- **las**: An object of class LAS or LAScatalog.
- **algorithm**: function. An algorithm of point decimation. lidR have: random, homogenize and highest.

Value

If the input is a LAS object, returns a LAS object. If the input is a LAScatalog, returns a LAScatalog.

Working with a LAScatalog

This section appears in each function that supports a LAScatalog as input.

In lidR when the input of a function is a LAScatalog the function uses the LAScatalog processing engine. The user can modify the engine options using the available options. A careful reading of the engine documentation is recommended before processing LAScatalogs. Each lidR function should come with a section that documents the supported engine options.

The LAScatalog engine supports .lax files that significantly improve the computation speed of spatial queries using a spatial index. Users should really take advantage a .lax files, but this is not mandatory.
Supported processing options

Supported processing options for a LAScatalog (in bold). For more details see the LAScatalog engine documentation:

- **chunk size**: How much data is loaded at once.
- chunk buffer: This function guarantee a strict wall-to-wall continuous output. The buffer option is not considered.
- **chunk alignment**: Align the processed chunks.
- **progress**: Displays a progression estimation.
- **output files**: Mandatory because the output is likely to be too big to be returned in R and needs to be written in las/laz files. Supported templates are {XLEFT}, {XRIGHT}, {YBOTTOM}, {YTOP}, {XCENTER}, {YCENTER} {ID} and, if chunk size is equal to 0 (processing by file), {ORIGINALFILENAME}.
- **select**: The function will write files equivalent to the original ones. Thus select = "*" and cannot be changed.
- **filter**: Read only points of interest.

Examples

```r
LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
las = readLAS(LASfile, select = "xyz")

# Select points randomly to reach an overall density of 1
thinned1 = lasfilterdecimate(las, random(1))
plot(grid_density(las))
plot(grid_density(thinned1))

# Select points randomly to reach an homogeneous density of 1
thinned2 = lasfilterdecimate(las, homogenize(1,5))
plot(grid_density(thinned2))

# Select the highest point within each pixel of an overlayed grid
thinned3 = lasfilterdecimate(las, highest(5))
plot(thinned3)
```

---

**lasfilterduplicates**  
*Filter duplicated points*

**Description**

Filter points that appear more than once in the point cloud according to their X Y Z coordinates

**Usage**

`lasfilterduplicates(las)  

```r
lasfilterduplicates(las)
```
Arguments

las An object of class LAS or LAScatalog.

Value

If the input is a LAS object, returns a LAS object. If the input is a LAScatalog, returns a LAScatalog.

Working with a LAScatalog

This section appears in each function that supports a LAScatalog as input.

In lidR when the input of a function is a LAScatalog the function uses the LAScatalog processing engine. The user can modify the engine options using the available options. A careful reading of the engine documentation is recommended before processing LAScatalogs. Each lidR function should come with a section that documents the supported engine options.

The LAScatalog engine supports .lax files that significantly improve the computation speed of spatial queries using a spatial index. Users should really take advantage a .lax files, but this is not mandatory.

Supported processing options

Supported processing options for a LAScatalog (in bold). For more details see the LAScatalog engine documentation:

- **chunk size**: How much data is loaded at once.
- chunk buffer: This function guarantees a strict wall-to-wall continuous output. The buffer option is not considered.
- **chunk alignment**: Align the processed chunks.
- **progress**: Displays a progression estimation.
- **output files**: Mandatory because the output is likely to be too big to be returned in R and needs to be written in las/laz files. Supported templates are {XLEFT}, {XRIGHT}, {YBOTTOM}, {YTOP}, {XCENTER}, {YCENTER} {ID} and, if chunk size is equal to 0 (processing by file), {ORIGINALFILENAME}.
- select: The function will write files equivalent to the original ones. Thus select = "*" and cannot be changed.
- **filter**: Read only points of interest.

See Also

Other lasfilters: lasfiltersurfacepoints(), lasfilters, lasfilter()
**lasfilters**

---

**Predefined filters**

**Description**
Select only some returns

**Usage**
- lasfilterfirst(las)
- lasfilterfirstlast(las)
- lasfilterfirstofmany(las)
- lasfilterground(las)
- lasfilterlast(las)
- lasfilternth(las, n)
- lasfiltersingle(las)
- lasfilterfirstofmany(las)

**Arguments**
- las An object of class [LAS](#)
- n the position in the return sequence

**Details**
- lasfilterfirst Select only the first returns.
- lasfilterfirstlast Select only the first and last returns.
- lasfilterground Select only the returns classified as ground according to LAS specification.
- lasfilterlast Select only the last returns i.e. the last returns and the single returns.
- lasfilternth Select the returns from their position in the return sequence.
- lasfilterfirstofmany Select only the first returns from pulses which returned multiple points.
- lasfiltersingle Select only the returns that return only one point.

**Value**
An object of class [LAS](#)
See Also

Other lasfilters: lasfilterduplicates(), lasfiltersurfacepoints(), lasfilter()

Examples

LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
lidar = readLAS(LASfile)

firstReturns = lasfilterfirst(lidar)
groundReturns = lasfilterground(lidar)

Description

This function is superseded by the algorithm highest usable in lasfilterdecimate

Usage

lasfiltersurfacepoints(las, res)

Arguments

las An object of class LAS or LAScatalog.
res numeric. The resolution of the grid used to filter the point cloud

Value

If the input is a LAS object, returns a LAS object. If the input is a LASCatalog, returns a LASCatalog.
Supported processing options

Supported processing options for a LAScatalog (in bold). For more details see the LAScatalog engine documentation:

- **chunk size**: How much data is loaded at once.
- **chunk buffer**: This function guarantees a strict wall-to-wall continuous output. The buffer option is not considered.
- **chunk alignment**: Align the processed chunks.
- **progress**: Displays a progression estimation.
- **output files**: Mandatory because the output is likely to be too big to be returned in R and needs to be written in las/laz files. Supported templates are \{XLEFT\}, \{XRIGHT\}, \{YBOTTOM\}, \{YTOP\}, \{XCENTER\}, \{YCENTER\} \{ID\} and, if chunk size is equal to 0 (processing by file), \{ORIGINALFILENAME\}.
- **select**: The function will write files equivalent to the original ones. Thus select = "*" and cannot be changed.
- **filter**: Read only points of interest.

See Also

Other lasfilters: lasfilterduplicates(), lasfilters, lasfilter()

Examples

```r
LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
las = readLAS(LASfile)
subset = lasfiltersurfacepoints(las, 2)
plot(subset)
```

---

`lasground` *Classify points as 'ground' or 'not ground'*

**Description**

Classify points as 'ground' or 'not ground' with several possible algorithms. The function updates the attribute `Classification` of the LAS object. The points classified as 'ground' are assigned a value of 2 according to las specifications.

**Usage**

`lasground(las, algorithm, last_returns = TRUE)`
Arguments

- las: An object of class LAS or LAScatalog.
- algorithm: a ground-segmentation function. lidR has: pmf and csf.
- last_returns: logical. The algorithm will use only the last returns (including the first returns in cases of a single return) to run the algorithm. If FALSE all the returns are used. If the attribute 'ReturnNumber' or 'NumberOfReturns' are absent, 'last_returns' is turned to FALSE automatically.

Value

If the input is a LAS object, return a LAS object. If the input is a LAScatalog, returns a LAScatalog.

Working with a LAScatalog

This section appears in each function that supports a LAScatalog as input.

In lidR when the input of a function is a LAScatalog the function uses the LAScatalog processing engine. The user can modify the engine options using the available options. A careful reading of the engine documentation is recommended before processing LAScatalogs. Each lidR function should come with a section that documents the supported engine options.

The LAScatalog engine supports .lax files that significantly improve the computation speed of spatial queries using a spatial index. Users should really take advantage a .lax files, but this is not mandatory.

Supported processing options

Supported processing options for a LAScatalog (in bold). For more details see the LAScatalog engine documentation:

- **chunk size**: How much data is loaded at once.
- **chunk buffer**: Mandatory to get a continuous output without edge effects. The buffer is always removed once processed and will never be returned either in R or in files.
- **chunk alignment**: Align the processed chunks.
- **progress**: Displays a progression estimation.
- **output files**: Mandatory because the output is likely to be too big to be returned in R and needs to be written in las/laz files. Supported templates are {XLEFT}, {XRIGHT}, {YBOTTOM}, {YTOP}, {XCENTER}, {YCENTER}, {ID} and, if chunk size is equal to 0 (processing by file), {ORIGINALFILENAME}.
- **select**: The function will write files equivalent to the original ones. Thus select = "*" and cannot be changed.
- **filter**: Read only points of interest.
Examples

LASfile <- system.file("extdata", "Topography.laz", package="lidR")
las <- readLAS(LASfile, select = "xyzrn")

# Using the Progressive Morphological Filter
# --------------------------------------
ws <- seq(3,12, 3)
th <- seq(0.1, 1.5, length.out = length(ws))
las <- lasground(las, pmf(ws, th))
plot(las, color = "Classification")

#' # Using the Cloth Simulation Filter
#' # --------------------------------------

#' (Parameters chosen mainly for speed)
mycsf <- csf(TRUE, 1, 1, time_step = 1)
las <- lasground(las, mycsf)
plot(las, color = "Classification")

---

LASheader Create a LASheader object

Description

Create a LASheader object

Usage

LASHeader(data = list())

Arguments

data a list containing the data from the header of a las file.

Value

An object of class LASheader
LASHeader-class

An S4 class to represent the header of .las or .laz files

Description

An S4 class to represent the header of .las or .laz files according to the LAS file format specifications. A LASHeader object contains a list in the slot @PHB with the data read from the Public Header Block and list in the slot @VLR with the data read from the Variable Length Records.

Slots

- PHB: list. Represents the Public Header Block
- VLR: list. Represents the Variable Length Records

lasmergespatial

Merge a point cloud with a source of spatial data

Description

Merge a point cloud with a source of spatial data. It adds an attribute along each point based on a value found in the spatial data. Sources of spatial data can be a SpatialPolygonsDataFrame or a RasterLayer.

- SpatialPolygonsDataFrame: it checks if the points belongs within each polygon. If the parameter attribute is the name of an attribute in the table of attributes of the shapefile, it assigns to the points the values of that attribute. Otherwise it classifies the points as boolean. TRUE if the points are in a polygon, FALSE otherwise.
- RasterLayer: it attributes to each point the value found in each pixel of the RasterLayer.
- RasterStack or RasterBrick must have 3 channels for RGB colors. It colorizes the point cloud with RGB values.

Usage

lasmergespatial(las, source, attribute = NULL)

Arguments

- las: An object of class LAS
- source: An object of class SpatialPolygonsDataFrame or RasterLayer or a RasterStack or RasterBrick with RGB colors.
- attribute: character. The name of an attribute in the table of attributes of the shapefile or the name of a new column in the LAS object. Not relevant for RGB colorization.
Value

An object of the class LAS.

Examples

```r
LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
shp <- system.file("extdata", "lake_polygons_UTM17.shp", package = "lidR")

las <- readLAS(LASfile)
lakes <- shapefile(shp)

# The attribute "inlake" does not exist in the shapefile.
# Points are classified as TRUE if in a polygon
las <- lasmergespatial(las, lakes, "inlakes")  # New attribute 'inlakes' is added.
forest <- lasfilter(las, inlakes == FALSE)
plot(las)
plot(forest)

# The attribute "LAKENAME_1" exists in the shapefile.
# Points are classified with the values of the polygons
las <- lasmergespatial(las, lakes, "LAKENAME_1")  # New column 'LAKENAME_1' is added.
```

---

**lasnormalize**  
**Remove the topography from a point cloud**

**Description**

Subtract digital terrain model (DTM) from LiDAR point cloud to create a dataset normalized with the ground at 0. The DTM can originate from an external file or can be computed by the user. It can also be computed on-the-fly. In this case the algorithm does not use rasterized data and each point is interpolated. There is no inaccuracy due to the discretization of the terrain and the resolution of the terrain is virtually infinite.

How well the edges of the dataset are interpolated depends on the interpolation method used. Thus, a buffer around the region of interest is always recommended to avoid edge effects.

The attribute Z of the returned LAS object is the normalized elevation. A new attribute 'Zref' records the former elevation values, which enables the use of lasunnormalize to restore original point elevations.

**Usage**

```r
lasnormalize(las, algorithm, na.rm = FALSE, use_class = c(2L, 9L), ...)
lasunnormalize(las)
```
## S4 method for signature 'LAS, RasterLayer'
e1 - e2

## S4 method for signature 'LAS, function'
e1 - e2

### Arguments

- **las**: An object of class LAS or LAScatalog.
- **algorithm**: a spatial interpolation function. lidR have tin, kriging, knnidw or a RasterLayer representing a digital terrain model (can be computed with grid_terrain)
- **na.rm**: logical. When using a RasterLayer as DTM, by default the function fails if a point fall in an empty pixel because a Z elevation cannot be NA. If na.rm = TRUE points with an elevation of NA are filtered. Be careful this creates a copy of the point cloud.
- **use_class**: integer vector. By default the terrain is computed by using ground points (class 2) and water points (class 9). Relevant only for a normalisation without a raster DTM.
- **...**: If algorithm is a RasterLayer, ... is propagated to extract. Typically one may use method = "bilinear".
- **e1**: a LAS object
- **e2**: RasterLayer representing a digital terrain model (can be computed with grid_terrain) or a spatial interpolation function. lidR has tin, kriging, and knnidw.

### Value

If the input is a LAS object, return a LAS object. If the input is a LAScatalog, returns a LAScatalog.

### Working with a LAScatalog

This section appears in each function that supports a LAScatalog as input.

In lidR when the input of a function is a LAScatalog the function uses the LAScatalog processing engine. The user can modify the engine options using the available options. A careful reading of the engine documentation is recommended before processing LAScatalogs. Each lidR function should come with a section that documents the supported engine options.

The LAScatalog engine supports .lax files that significantly improve the computation speed of spatial queries using a spatial index. Users should really take advantage a .lax files, but this is not mandatory.

### Supported processing options

Supported processing options for a LAScatalog (in bold). For more details see the LAScatalog engine documentation:
• **chunk size**: How much data is loaded at once.

• **chunk buffer**: Mandatory to get a continuous output without edge effects. The buffer is always removed once processed and will never be returned either in R or in files.

• **chunk alignment**: Align the processed chunks.

• **progress**: Displays a progression estimation.

• **output files**: Mandatory because the output is likely to be too big to be returned in R and needs to be written in las/laz files. Supported templates are \{XLEFT\}, \{XRIGHT\}, \{YBOTTOM\}, \{YTOP\}, \{XCENTER\}, \{YCENTER\} \{ID\} and, if chunk size is equal to 0 (processing by file), \{ORIGINALFILENAME\}.

• **select**: The function will write files equivalent to the original ones. Thus select = "*" and cannot be changed.

• **filter**: Read only points of interest.

**See Also**

raster grid_terrain

**Examples**

```r
LASfile <- system.file("extdata", "Topography.laz", package="lidR")
las <- readLAS(LASfile)

plot(las)

# First option: use a RasterLayer as DTM
# ==============================================================
dtm <- grid_terrain(las, 1, knnidw(k = 6L, p = 2))
las <- lasnormalize(las, dtm)

plot(dtm)
plot(las)

# restore original elevations
las <- lasunnormalize(las)
plot(las)

# operator - can be used. This is equivalent to the previous
las <- las - dtm
plot(las)

# restore original elevations
las <- lasunnormalize(las)

# Second option: interpolate each point (no discretization)
# ==============================================================
las <- lasnormalize(las, tin())
plot(las)
```
laspulse

Retrieve individual pulses, flightlines or scanlines

Description

Retrieve each individual pulse, individual flightline or individual scanline and assigns a number to each point. The LAS object must be properly populated according to LAS specifications otherwise users could find unexpected outputs.

Usage

```r
laspulse(las)
lasflightline(las, dt = 30)
lasscanline(las)
```

Arguments

- **las**: A LAS object
- **dt**: numeric. The threshold time-lag used to retrieve flightlines

Details

- **laspulse**: Retrieves each individual pulse. It uses GPS time. An attribute pulseID is added in the LAS object
- **lasscanline**: Retrieves each individual scanline. When data are sampled according to a saw-tooth pattern (oscillating mirror), a scanline is one line, or row of data. The function relies on the GPS field time to order the data. Then, the ScanDirectionFlag attribute is used to retrieve each scanline. An attribute scanlineID is added in the LAS object
lasflightline  Retrieves each individual flightline. It uses GPS time. In a continuous dataset, once points are ordered by GPS time, the time between two consecutive points does not exceed a few milliseconds. If the time between two consecutive points is too long it means that the second point is from a different flightline. The default threshold is 30 seconds. An attribute flightlineID is added in the LAS object.

Value
An object of class LAS

Examples
LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
las <- readLAS(LASfile)
las <- laspulse(las)
las <- lasflightline(las)
plot(las, color = "flightlineID")

lasrangecorrection  Normalize intensity with a range correction

Description
Normalize intensity with a range correction according to the formula (see references):

\[ I_{\text{norm}} = I_{\text{obs}} \left( \frac{R}{R_s} \right)^f \]

To achieve the range correction the position of the sensor must be known at different discrete times. Using the 'gpstime' of each point, the position of the sensor is interpolated from the reference and a range correction is applied.

Usage
lasrangecorrection(
  las,
  sensor,
  Rs,
  f = 2.3,
  gpstime = "gpstime",
  elevation = "Z"
)
Rescale and reoffset a LAS object

Modify the scale factor and the offset of a LAS object. This function modify the header and recompute the coordinates. Coordinates might be moved by few tenth of millimeters or few millimeters depending of the accuracy imposed by the user.
Usage

\begin{verbatim}
lasrescale(las, xscale, yscale, zscale)
lasreoffset(las, xoffset, yoffset, zoffset)
\end{verbatim}

Arguments

\begin{verbatim}
las An object of class LAS
xscale, yscale, zscale scalar. Can be missing if not relevant.
xoffset, yoffset, zoffset scalar. Can be missing if not relevant.
\end{verbatim}

Examples

\begin{verbatim}
LASfile <- system.file("extdata", "example.laz", package = "rlas")
las <- readLAS(LASfile)

las <- lasrescale(las, xscale = 0.01, yscale = 0.01)
las <- lasreoffset(las, xoffset = 300000, yoffset = 5248000)
\end{verbatim}

\begin{verbatim}
lassmooth

Smooth a point cloud

\end{verbatim}

Description

Point cloud-based smoothing algorithm. Two methods are available: average within a window and Gaussian smooth within a window. The attribute \texttt{Z} of the returned LAS object is the smoothed \texttt{Z}. A new attribute \texttt{Zraw} is added to store the original values and can be used to restore the point cloud with \texttt{lasunsmooth}.

Usage

\begin{verbatim}
lassmooth(
    las,
    size,
    method = c("average", "gaussian"),
    shape = c("circle", "square"),
    sigma = size/6
)

lasunsmooth(las)
\end{verbatim}
lassnags

Arguments

las An object of class LAS
size numeric. The size of the windows used to smooth.
method character. Smoothing method. Can be ‘average’ or ‘gaussian’.
shape character. The shape of the windows. Can be circle or square.
sigma numeric. The standard deviation of the gaussian if the method is gaussian.

Details

This method does not use raster-based methods to smooth the point cloud. This is a true point cloud smoothing. It is not really useful by itself but may be interesting in combination with filters such as lasfiltersurfacepoints, for example to develop new algorithms.

Value

An object of the class LAS.

See Also

lasfiltersurfacepoints

Examples

LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
las <- readLAS(LASfile, select = "xyz")
las <- lasfiltersurfacepoints(las, 1)
plot(las)

las <- lassmooth(las, 5, "gaussian", "circle", sigma = 2)
plot(las)

las <- lasunsmooth(las)
plot(las)

lassnags  Snag classification

Description

Snag classification/segmentation using several possible algorithms (see details). The function attributes a number identifying a snag class (snagCls attribute) to each point of the point cloud. The classification/segmentation is done at the point cloud level and currently only one algorithm implemented, which uses LiDAR intensity thresholds and specified neighborhoods to differentiate bole and branch from foliage points (see details).
Usage

lassnags(las, algorithm, attribute = "snagCls")

Arguments

las An object of class LAS or LAScatalog.
attribute character. The returned LAS object automatically has a new attribute (a new column). This parameter is the name of this new attribute.

Value

If the input is a LAS object, return a LAS object. If the input is a LAScatalog, returns a LAScatalog.

Working with a LAScatalog

This section appears in each function that supports a LAScatalog as input.

In lidR when the input of a function is a LAScatalog the function uses the LAScatalog processing engine. The user can modify the engine options using the available options. A careful reading of the engine documentation is recommended before processing LAScatalogs. Each lidR function should come with a section that documents the supported engine options.

The LAScatalog engine supports .lax files that significantly improve the computation speed of spatial queries using a spatial index. Users should really take advantage a .lax files, but this is not mandatory.

Supported processing options

Supported processing options for a LAScatalog (in bold). For more details see the LAScatalog engine documentation:

- **chunk size**: How much data is loaded at once.
- **chunk buffer**: Mandatory to get a continuous output without edge effects. The buffer is always removed once processed and will never be returned either in R or in files.
- **chunk alignment**: Align the processed chunks.
- **progress**: Displays a progression estimation.
- **output files**: Mandatory because the output is likely to be too big to be returned in R and needs to be written in las/laz files. Supported templates are {XLEFT}, {XRIGHT}, {YBOTTOM}, {YTOP}, {XCENTER}, {YCENTER} {ID} and, if chunk size is equal to 0 (processing by file), {ORIGINALFILENAME}.
- **select**: The function will write files equivalent to the original ones. Thus select = "*" and cannot be changed.
- **filter**: Read only points of interest.
Examples

```r
## Not run:
LASfile <- system.file("extdata", "MixedConifer.laz", package="lidR")
las <- readLAS(LASfile, select = "xyzi", filter="-keep_first") # Wing also included -keep_single

# For the Wing2015 method, supply a matrix of snag BranchBolePtRatio conditional
# assessment thresholds (see Wing et al. 2015, Table 2, pg. 172)
bbpr_thresholds <- matrix(c(0.80, 0.80, 0.70,
                            0.85, 0.85, 0.60,
                            0.80, 0.80, 0.60,
                            0.90, 0.90, 0.55),
                           nrow =3, ncol = 4)

# Run snag classification and assign classes to each point
las <- lassnags(las, wing2015(neigh_radii = c(1.5, 1, 2), BBPRthrsh_mat = bbpr_thresholds))

# Plot it all, tree and snag points...
plot(las, color="snagCls", colorPalette = rainbow(5))

# Filter and plot snag points only
snags <- lasfilter(las, snagCls > 0)
plot(snags, color="snagCls", colorPalette = rainbow(5)[-1])

# Wing et al's (2015) methods ended with performing tree segmentation on the
# classified and filtered point cloud using the watershed method

## End(Not run)
```

---

**lastransform**

*Datum transformation for LAS objects*

**Description**

A version of `spTrasform` for LAS objects. Returns transformed coordinates of a LAS object from the projection of the object to the the projection given by arguments.

**Usage**

```r
lastransform(las, CRSobj)
```

**Arguments**

- `las` An object of class LAS
- `CRSobj` logical. Object of class CRS or of class character, in which case it is converted to CRS.
Value
An object of class LAS with coordinates XY transformed to the new coordinate reference system. The header has been updated by add the ESPG code or a WKT OGC CS string as a function of the defined Global Encoding WKT bit (see LAS specifications).

Examples

```r
LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
las <- readLAS(LASfile, select = "xyzrn")
crs <- sp::CRS("init=epsg:26918")
las <- lastransform(las, crs)
```

Description
Individual tree segmentation with several possible algorithms. The returned point cloud has a new extra byte attribute named after the parameter attribute independently of the algorithm used.

Usage

```r
lastrees(las, algorithm, attribute = "treeID")
```

Arguments

<table>
<thead>
<tr>
<th>Argument</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>las</td>
<td>An object of class LAS.</td>
</tr>
<tr>
<td>algorithm</td>
<td>function. An algorithm of individual tree segmentation. lidR has: dalponte2016, watershed, mcwatershed, li2012 and silva2016. More experimental algorithms may be found in the package lidRplugins</td>
</tr>
<tr>
<td>attribute</td>
<td>character. The returned LAS object as a new extra byte attribute (in a new column). This parameter controls the name of the new attribute. Default is &quot;treeID&quot;.</td>
</tr>
</tbody>
</table>

Value
An object of the class LAS

Examples

```r
LASfile <- system.file("extdata", "MixedConifer.laz", package="lidR")
las <- readLAS(LASfile, select = "xyz", filter = "-drop_z_below 0")

# Using Li et al. (2012)
las <- lastrees(las, li2012(R = 3, speed_up = 5))
plot(las, color = "treeID")
```
Description
Reduce the number of points by voxelizing the point cloud. If the Intensity is part of the attributes it is preserved and aggregated as \(\text{mean(Intensity)}\). Other attributes cannot be aggregated and are lost.

Usage
\[
\text{lasvoxelize(las, res)}
\]

Arguments
- \text{las}: An object of class \text{LAS} or \text{LAScatalog}.
- \text{res}: numeric. The resolution of the voxels. \(\text{res} = 1\) for a 1x1x1 cubic voxels. Optionally \(\text{res} = \langle 1, 2 \rangle\) for non-cubic voxels (1x1x2 cuboid voxel).

Value
If the input is a LAS object, returns a LAS object. If the input is a LAScatalog, returns a LAScatalog.

Working with a LAScatalog
This section appears in each function that supports a LAScatalog as input.

In \text{lidR} when the input of a function is a LAScatalog the function uses the LAScatalog processing engine. The user can modify the engine options using the available options. A careful reading of the engine documentation is recommended before processing LAScatalogs. Each \text{lidR} function should come with a section that documents the supported engine options.

The LAScatalog engine supports .lax files that \textit{significantly} improve the computation speed of spatial queries using a spatial index. Users should really take advantage a .lax files, but this is not mandatory.

Supported processing options
Supported processing options for a LAScatalog (in bold). For more details see the LAScatalog engine documentation:

- \textbf{chunk size}: How much data is loaded at once.
- \textbf{chunk buffer}\(^*\): Mandatory to get a continuous output without edge effects. The buffer is always removed once processed and will never be returned either in R or in files.
- \textbf{chunk alignment}: Align the processed chunks.
• **progress**: Displays a progression estimation.

• **output files**: Mandatory because the output is likely to be too big to be returned in R and needs to be written in las/laz files. Supported templates are {XLEFT}, {XRIGHT}, {YBOTTOM}, {YTOP}, {XCENTER}, {YCENTER} {ID} and, if chunk size is equal to 0 (processing by file), {ORIGINALFILENAME}.

• **select**: The function will write files equivalent to the original ones. Thus select = "*" and cannot be changed.

• **filter**: Read only points of interest.

**Examples**

```r
LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
las = readLAS(LASfile, select = "xyz")
las2 = lasvoxelize(las, 2)
plot(las2)
```

---

**li2012**  
*Individual Tree Segmentation Algorithm*

**Description**

This functions is made to be used in `lastrees`. It implements an algorithm for tree segmentation based on the Li et al. (2012) article (see reference). This method is a growing region method working at the point cloud level. It is an implementation, as strict as possible, made by the lidR author but with the addition of a parameter `hmin` to prevent over-segmentation for objects that are too low.

**Usage**

```r
li2012(dt1 = 1.5, dt2 = 2, R = 2, Zu = 15, hmin = 2, speed-up = 10)
```

**Arguments**

- `dt1`: numeric. Threshold number 1. See reference page 79 in Li et al. (2012). Default is 1.5.
- `R`: numeric. Search radius. See page 79 in Li et al. (2012). Default is 2. If `R = 0` all the points are automatically considered as local maxima and the search step is skipped (much faster).
- `Zu`: numeric. If point elevation is greater than Zu, `dt2` is used, otherwise `dt1` is used. See page 79 in Li et al. (2012). Default is 15.
- `speed_up`: numeric. Maximum radius of a crown. Any value greater than a crown is good because this parameter does not affect the result. However, it greatly affects the computation speed. The lower the value, the faster the method. Default is 10.
References


See Also

Other individual tree segmentation algorithms: `dalponte2016()`, `silva2016()`, `watershed()`

Examples

```r
LASfile <- system.file("extdata", "MixedConifer.laz", package="lidR")
las <- readLAS(LASfile, select = "xyz", filter = "-drop_z_below 0")
col <- pastel.colors(200)

las <- lastrees(las, li2012(dt1 = 1.4))
plot(las, color = "treeID", colorPalette = col)
```

Description

This document explains how objects are written on disk when processing a LAScatalog. As mentioned in `LAScatalog-class`, users can set a templated filename to store the outputs on disk instead of in R memory. By default LAS objects are stored in .las files with `writeLAS`, Raster* objects are stored in .tif files with `writeRaster`, Spatial* objects are stored in .shp files with `writeOGR`, data.frame objects are stored in .csv files with `fwrite`, and other objects are not supported. However, users can modify all these default settings and even add new drivers. This manual page explain how. One may also refer to some unofficial documentation [here](#) or [here](#).

Generic form of a driver

A driver is stored in the `@output_options` slot of a LAScatalog. It is a list that contains:

- **write** A function that receives an object and a path, and writes the object into a file using the path. The function can also have extra options.
- **extension** A string that gives the file extension.
- **object** A string that gives the name of the argument used to pass the object to write in the function used to write the object.
- **path** A string that gives the name of the argument used to pass the path of the file to write in the function used to write the object.
- **param** A labelled list of extra parameters for the function used to write the object.

For example, the driver to write a Raster* is
list(
    write = raster::writeRaster,
    extension = ".tif",
    object = "x",
    path = "filename",
    param = list(format = "GTiff"))

And the driver to write a LAS is

list(
    write = lidR::writeLAS,
    extension = ".las",
    object = "las",
    path = "file",
    param = list())

Modify a driver (1/2)

Users can modify the drivers to write different file types than the default. For example, to write in GeoPackage instead of shapefile, one must change the Spatial driver:

ctg@output_options$drivers$Spatial$extension <- ".gpkg"

To write in .grd files instead of .tif files one must change the Raster driver:

ctg@output_options$drivers$Raster$extension <- ".grd"
ctg@output_options$drivers$Raster$param$format <- "raster"

To write in .laz files instead of .las files one must change the LAS driver:

ctg@output_options$drivers$LAS$extension <- ".laz"

Add a new driver

The drivers allow LAS, Spatial*, Raster* and data.frame objects to be written. When using the engine (catalog_apply) to build new tools, users may need to be able to write other objects such as a list. To do that users need to add a list element into the output_options:

ctg@output_options$drivers$list = list(
    write = base::saveRDS,
    object = "object",
    path = "file",
    extension = ".rds",
    param = list(compress = TRUE))

The LAScatalog now has a new driver capable of writing a list.
Modify a driver (2/2)

It is also possible to completely overwrite an existing driver. By default SpatialPointsDataFrame objects are written into ESRI shapefiles with writeOGR. writeOGR can write into other file types, such as GeoPackage or GeoJSON and even as SQLite database objects. But it cannot add data into an existing SQLite database. Let’s create our own driver for a SpatialPointsDataFrame. First we need a function able to write and append a SpatialPointsDataFrame into a SQLite database from the object and the path.

```r
dbName_SpatialPointsDataFrame = function(x, path, name)
{
  x <- as.data.frame(x)
  con <- RSQLite::dbConnect(RSQLite::SQLite(), path)
  RSQLite::dbWriteTable(con, name, x, append = TRUE)
  RSQLite::dbDisconnect(con)
}
```

Then we create the driver. User-defined drivers supersede default drivers:

```r
ctg@output_options$drivers$SpatialPointsDataFrame = list(
  write = dbName_SpatialPointsDataFrame,
  extension = ".sqlite",
  object = "x",
  path = "path",
  param = list(name = "layername"))
```

Then to be sure that we do not write several .sqlite files, we don’t use templated filename.

```r
opt_output_files(ctg) <- paste0(tempdir(), "/mysqlitefile")
```

And all the SpatialPointsDataFrame will be appended in a single database.

---

**lidR-parallelism**  
*Parallel computation in lidR*

**Description**

This document explains how to process point clouds taking advantage of parallel processing in the lidR package. The lidR package has two levels of parallelism, which is why it is difficult to understand how it works. This page aims to provide users with a clear overview of how to take advantage of multicore processing even if they are not comfortable with the parallelism concept.
Algorithm-based parallelism

When processing a point cloud we are applying an algorithm on data. This algorithm may or may not be natively parallel. In lidR some algorithms are fully computed in parallel, but some are not because they are not parallelizable, while some are only partially parallelized. It means that some portions of the code are computed in parallel and some are not. When an algorithm is natively parallel in lidR it is always a C++ based parallelization with OpenMP. The advantage is that the computation is faster without any consequence for memory usage because the memory is shared between the processors. In short, algorithm-based parallelism provides a significant gain without any cost for your R session and your system (but obviously there is a greater workload for the processors). By default lidR uses half of your cores but you can control this with set_lidr_threads. For example, the lmf algorithm is natively parallel. The following code is computed in parallel:

```r
las <- readLAS("file.las")
tops <- tree_detection(las, lmf(2))
```

However, as stated above, not all algorithms are parallelized or even parallelizable. For example, li2012 is not parallelized. The following code is computed in serial:

```r
las <- readLAS("file.las")
dtm <- lastrees(las, li2012())
```

To know which algorithms are parallelized users can refer to the documentation or use the function is.parallelised.

```r
is.parallel(lmf(2)) #> TRUE
is.parallel(li2012()) #> FALSE
```

cunk-based parallelism

When processing a LAScatalog, the internal engine splits the dataset into chunks and each chunk is read and processed sequentially in a loop. But actually this loop can be parallelized with the future package. By default the chunks are processed sequentially, but they can be processed in parallel by registering an evaluation strategy. For example, the following code is evaluated sequentially:

```r
ctg <- readLAScatalog("folder/")
out <- grid_metrics(ctg, mean(Z))
```

But this one is evaluated in parallel with two cores:

```r
library(future)
plan(multisession, workers = 2L)
ctg <- readLAScatalog("folder/")
out <- grid_metrics(ctg, mean(Z))
```

With chunk-based parallelism any algorithm can be parallelized by processing several subsets of a dataset. However, there is a strong cost associated with this type of parallelism. When processing several chunks at a time, the computer needs to load the corresponding point clouds. Assuming the user processes one square kilometer chunks in parallel with 4 cores, then 4 chunks are loaded in the computer memory. This may be too much and the speed-up is not guaranteed since there is some overhead involved in reading several files at a time. Once this point is understood, chunk-based parallelism is very powerful since all the algorithms can be parallelized whether or not they are natively parallel.
Nested parallelism - part 1

Previous sections stated that some algorithms are natively parallel, such as `lmf`, and some are not, such as `ll2012`. Anyway, users can split the dataset into chunks to process them simultaneously with the LASCatalog processing engine. Let’s assume that the user’s computer has four cores, what happens in this case:

```r
library(future)
plan(multisession, workers = 4L)
set_lidr_threads(4L)
ctg <- readLAScatalog("folder/")
out <- tree_detection(ctg, lmf(2))
```

Here the catalog will be split into chunks that will be processed in parallel. And each computation itself implies a parallelized task. This is a nested parallelism task and it is bad! Hopefully the lidR package handles such cases and chooses by default to give precedence to chunk-based parallelism. In this case chunks will be processed in parallel and the points will be processed serially. The question of nested parallel loops is irrelevant. The catalog processing engine has precedence rules that are guaranteed to avoid nested parallelism. This precedence rule aims to (1) always work (2) preserve behaviors of lidR version 2.0.y.

Nested parallelism - part 2

We explained rules of precedence. But actually the user can tune the engine more accurately. Let’s define the following function:

```r
myfun = function(cluster, ...)
{
  las <- readLAS(cluster)
  if (is.empty(las)) return(NULL)
  las <- lasnormalize(las, tin())
  tops <- tree_detection(las, lmf(2))
  bbox <- extent(cluster)
  tops <- crop(tops, bbox)
  return(tops)
}
```

```r
out <- catalog_apply(ctg, myfun, ws = 5)
```

This function used two algorithms, one is partially parallelized (`tin`) and one is fully parallelized `lmf`. The user can manually use both OpenMP and future. By default the engine will give precedence to chunk-based parallelism because it works in all cases but the user can impose something else. In the following 2 workers are attributed to future and 2 workers are attributed to OpenMP.

```r
plan(multisession, workers = 2L)
set_lidr_threads(2L)
catalog_apply(ctg, myfun, ws = 5)
```

The rule is simple. If the number of workers needed is greater than the number of available workers then OpenMP is disabled. Let suppose we have a quadcore machine:
# 2 chunks 2 threads: OK
plan(multisession, workers = 2L)
set_lidr_threads(2L)

# 4 chunks 1 threads: OK
plan(multisession, workers = 4L)
set_lidr_threads(1L)

# 1 chunks 4 threads: OK
plan(sequential)
set_lidr_threads(4L)

# 3 chunks 2 threads: NOT OK
# Needs 6 workers, OpenMP threads are set to 1 i.e. sequential processing
plan(multisession, workers = 3L)
set_lidr_threads(2L)

---

**lidrpalettes** | **Palettes**
--- | ---

**Description**
Create a vector of n contiguous (or not) colors

**Usage**
- height.colors(n)
- forest.colors(n)
- random.colors(n)
- pastel.colors(n)

**Arguments**
- n The number of colors (> 1) to be in the palette

**See Also**
- `grDevices::Palettes`
Individual Tree Detection Algorithm

Description

This function is made to be used in `tree_detection`. It implements an algorithm for tree detection based on a local maximum filter. The windows size can be fixed or variable and its shape can be square or circular. The internal algorithm works either with a raster or a point cloud. It is deeply inspired by Popescu & Wynne (2004) (see references).

Usage

```r
lmf(ws, hmin = 2, shape = c("circular", "square"))
```

Arguments

- `ws`
  - numeric or function. Length or diameter of the moving window used to detect the local maxima in the units of the input data (usually meters). If it is numeric a fixed window size is used. If it is a function, the function determines the size of the window at any given location on the canopy. The function should take the height of a given pixel or point as its only argument and return the desired size of the search window when centered on that pixel/point.

- `hmin`
  - numeric. Minimum height of a tree. Threshold below which a pixel or a point cannot be a local maxima. Default is 2.

- `shape`
  - character. Shape of the moving window used to find the local maxima. Can be "square" or "circular".

References


See Also

Other individual tree detection algorithms: `manual()`

Examples

```r
LASfile <- system.file("extdata", "MixedConifer.laz", package="lidR")
las <- readLAS(LASfile, select = "xyz", filter = "-drop_z_below 0")
# point-cloud-based
# ===============

# 5x5 m fixed window size
ttops <- tree_detection(las, lmf(5))
```
# Individual Tree Detection Algorithm

## Description

This function is made to be used in `tree_detection`. It implements an algorithm for manual tree detection. Users can pinpoint the tree top positions manually and interactively using the mouse. This is only suitable for small-sized plots. First the point cloud is displayed, then the user is invited to select a rectangular region of interest in the scene using the right mouse button. Within the selected region the highest point will be flagged as 'tree top' in the scene. Once all the trees are labeled the user can exit the tool by selecting an empty region. Points can also be unflagged. The goal of this tool is mainly for minor correction of automatically-detected tree outputs.

## Usage

```r
manual(detected = NULL, radius = 0.5, color = "red", ...)```

```r
x <- plot(las)
add_treetops3d(x, tt)

# variable windows size
f <- function(x) (x * 0.07 + 3)
tt <- tree_detection(las, lmf(f))

x <- plot(las)
add_treetops3d(x, tt)

# raster-based
# ============

# 5x5 m fixed window size
chm <- grid_canopy(las, res = 1, p2r(0.15))
kern <- matrix(1,3,3)
chm <- raster::focal(chm, w = kern, fun = median, na.rm = TRUE)

tt <- tree_detection(chm, lmf(5))

plot(chm, col = height.colors(30))
plot(tt, add = TRUE)

# variable window size
f <- function(x) (x * 0.07 + 3)
tt <- tree_detection(chm, lmf(f))

plot(chm, col = height.colors(30))
plot(tt, add = TRUE)```
**Arguments**

- `detected` SpatialPointsDataFrame of already found tree tops that need manual correction.
- `radius` numeric. Radius of the spheres displayed on the point cloud (aesthetic purposes only).
- `color` character. Color of the spheres displayed on the point cloud (aesthetic purposes only).
- `...` supplementary parameters to be passed to `plot`.

**See Also**

Other individual tree detection algorithms: `lmf()`

**Examples**

```r
## Not run:
LASfile <- system.file("extdata", "MixedConifer.laz", package="lidR")
las = readLAS(LASfile)

# Full manual tree detection
ttops = tree_detection(las, manual())

# Automatic detection with manual correction
ttops = tree_detection(las, lmf(5))
ttops = tree_detection(las, manual(ttops))

## End(Not run)
```

---

**p2r**

*Digital Surface Model Algorithm*

**Description**

This function is made to be used in `grid_canopy`. It implements an algorithm for digital surface model computation based on a points-to-raster method: for each pixel of the output raster the function attributes the height of the highest point found. The `subcircle tweak` replaces each point with 8 points around the original one. This allows for virtual 'emulation' of the fact that a lidar point is not a point as such, but more realistically a disc. This tweak densifies the point cloud and the resulting canopy model is smoother and contains fewer 'pits' and empty pixels.

**Usage**

`p2r(subcircle = 0, na.fill = NULL)`
Arguments

subcircle numeric. Radius of the circles. To obtain fewer empty pixels the algorithm can replace each return with a circle composed of 8 points (see details).

na.fill function. A function that implements an algorithm to compute spatial interpolation to fill the empty pixel often left by points-to-raster methods. lidR has knnidw, tin, and kriging (see also grid_terrain for more details).

See Also

Other digital surface model algorithms: dsmtin(), pitfree()

Examples

LASfile <- system.file("extdata", "MixedConifer.laz", package="lidR")
las <- readLAS(LASfile)
col <- height.colors(50)

# Points-to-raster algorithm with a resolution of 1 meter
chm <- grid_canopy(las, res = 1, p2r())
plot(chm, col = col)

# Points-to-raster algorithm with a resolution of 0.5 meters replacing each # point by a 20 cm radius circle of 8 points
chm <- grid_canopy(las, res = 0.5, p2r(0.2))
plot(chm, col = col)

## Not run:
chm <- grid_canopy(las, res = 0.5, p2r(0.2, na.fill = tin()))
plot(chm, col = col)
## End(Not run)

pitfree Digital Surface Model Algorithm

Description

This function is made to be used in grid_canopy. It implements the pit-free algorithm developed by Khosravipour et al. (2014), which is based on the computation of a set of classical triangulations at different heights (see references). The subcircle tweak replaces each point with 8 points around the original one. This allows for virtual ‘emulation’ of the fact that a lidar point is not a point as such, but more realistically a disc. This tweak densifies the point cloud and the resulting canopy model is smoother and contains fewer ‘pits’ and empty pixels.

Usage

pitfree(thresholds = c(0, 2, 5, 10, 15), max_edge = c(0, 1), subcircle = 0)
arguments

thresholds numeric. Set of height thresholds according to the Khosravipour et al. (2014) algorithm description (see references)

max_edge numeric. Maximum edge length of a triangle in the Delaunay triangulation. If a triangle has an edge length greater than this value it will be removed. The first number is the value for the classical triangulation (threshold = 0, see also dsmtin), the second number is the value for the pit-free algorithm (for thresholds > 0). If max_edge = 0 no trimming is done (see examples).

subcircle numeric. radius of the circles. To obtain fewer empty pixels the algorithm can replace each return with a circle composed of 8 points (see details).

References


See Also

Other digital surface model algorithms: dsmtin(), p2r()

Examples

LASfile <- system.file("extdata", "MixedConifer.laz", package="lidR")
las <- readLAS(LASfile)
col <- height.colors(50)

# Basic triangulation and rasterization of first returns
chm <- grid_canopy(las, res = 0.5, dsmtin())
plot(chm, col = col)

# Khosravipour et al. pitfree algorithm
chm <- grid_canopy(las, res = 0.5, pitfree(c(0,2,5,10,15), c(0, 1.5)))
plot(chm, col = col)

## Not run:
# Potentially complex concave subset of point cloud
x = c(481340, 481340, 481280, 481300, 481280, 481340)
y = c(3812940, 3813000, 3813000, 3812960, 3812940, 3812940)
las2 = lasclipPolygon(las,x,y)
plot(las2)

# Since the TIN interpolation is done within the convex hull of the point cloud
# dummy pixels are interpolated that are strictly correct according to the interpolation method
# used, but meaningless in our CHM
chm <- grid_canopy(las2, res = 0.5, pitfree())
plot(chm, col = col)

chm = grid_canopy(las2, res = 0.5, pitfree(max_edge = c(3, 1.5)))
plot(chm, col = col)
## End(Not run)

---

**plot**

*Plot a LAS* object

### Description

Plot displays a 3D interactive windows-based on rgl for LAS objects

Plot displays an interactive view for LAScatalog objects with pan and zoom capabilities based on mapview. If the coordinate reference system (CRS) of the LAScatalog is non empty, the plot can be displayed on top of base maps (satellite data, elevation, street, and so on).

Plot displays a LASheader object exactly like it displays a LAScatalog object.

### Usage

```
plot(x, y, ...)
```

```
## S4 method for signature 'LAS,missing'
plot(
  x,
  y,
  color = "Z",
  colorPalette = "auto",
  bg = "black",
  trim = Inf,
  backend = c("rgl", "pcv"),
  clear_artifacts = TRUE,
  nbits = 16,
  axis = FALSE,
  legend = FALSE,
  ...
)
```

```
## S4 method for signature 'LAScatalog,missing'
plot(x, y, mapview = FALSE, chunk_pattern = FALSE, ...)
```

```
## S4 method for signature 'LASheader,missing'
plot(x, y, mapview = FALSE, ...)
```

### Arguments

- `x` A LAS* object
- `y` Unused (inherited from R base)
... Will be passed to points3d (LAS) or plot if mapview = FALSE or to mapview if mapview = TRUE (LAScatalog).

color characters. The attribute used to color the point cloud. Default is Z coordinates. RGB is an allowed string even if it refers to three attributes simultaneously.

colorPalette characters. A vector of colors such as that generated by heat.colors, topo.colors, terrain.colors or similar functions. Default is "auto" providing an automatic coloring depending on the argument color

bg The color for the background. Default is black.

trim numeric. Enables trimming of values when outliers break the color palette range. Every point with a value higher than trim will be plotted with the highest color.

backend character. Can be "rgl" or "pcv". If "rgl" is chosen the display relies on the rgl package. If "pcv" is chosen it relies on the PointCloudViewer package, which is much more efficient and can handle million of points using less memory. PointCloudViewer is not available on CRAN yet and should be installed from github (see. https://github.com/Jean-Romain/PointCloudViewer).

clear_artifacts logical. It is a known and documented issue that the 3D visualisation with rgl displays artifacts. The points look aligned and/or regularly spaced in some view angles. This is because rgl computes with single precision float. To fix that the point cloud is shifted to (0,0) to reduce the number of digits needed to represent its coordinates. The drawback is that the point cloud is not plotted at its actual coordinates.

nbits integer. If color = RGB it assumes that RGB colors are coded on 16 bits as described in the LAS format specification. However, this is not always respected. If the colors are stored on 8 bits set this parameter to 8.

axis logical. Display axis on XYZ coordinates.

legend logical. Display a gradient color legend.

mapview logical. If FALSE the catalog is displayed in a regular plot from R base.

chunk_pattern logical. Display the current chunk pattern used to process the catalog.

Examples

LASfile <- system.file("extdata", "MixedConifer.laz", package="lidR")
las <- readLAS(LASfile)

plot(las)
plot(las, color = "Intensity")

# If outliers break the color range, use the trim parameter
plot(las, color = "Intensity", trim = 150)

plot(las, color = "Classification")

# This dataset is already tree segmented
plot(las, color = "treeID")

# single file catalog using data provided in lidR
ctg = readLAScatalog(LASfile)
plot(ctg)

---

plot.lasmetrics3d  Plot voxelized LiDAR data

Description
This function implements a 3D plot method for 'lasmetrics3d' objects

Usage

## S3 method for class 'lasmetrics3d'
plot(
  x,
  y,
  color = "Z",
  colorPalette = height.colors(50),
  bg = "black",
  trim = Inf,
  ...
)

Arguments

x  An object of the class 'lasmetrics3d'
y  Unused (inherited from R base)
color  characters. The field used to color the points. Default is Z coordinates. Or a vector of colors.
colorPalette  characters. A color palette name. Default is height.colors provided by the package lidR
bg  The color for the background. Default is black.
trim  numeric. Enables trimming of values when outliers break the color palette range. Default is 1 meaning that the whole range of the values is used for the color palette. 0.9 means that 10 In this case the values higher than the 90th percentile are set to the highest color. They are not removed.
...  Supplementary parameters for points3d if the display method is "points".

See Also

voxel_metrics points3d height.colors forest.colors heat.colors colorRampPalette
Examples

```
LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
lidar = readLAS(LASfile)

voxels = voxel_metrics(lidar, list(Imean = mean(Intensity)))
plot(voxels, color = "Imean", colorPalette = heat.colors(50), trim=0.99)
```

Description

Add a RasterLayer object that represents a digital terrain model or a SpatialPointsDataFrame that represents tree tops to a point cloud scene. To add elements to a scene with a point cloud plotted with the function plot from lidR, the functions `add_*` take as first argument the output of the plot function (see examples), because the plot function does not plot the actual coordinates of the point cloud, but offsetted values. See function `plot` and its argument `clear_artifacts` for more details.

Usage

```
plot_dtm3d(dtm, bg = "black", clear_artifacts = TRUE, ...)
add_dtm3d(x, dtm, ...)
add_treetops3d(x, ttops, z = "Z", ...)
add_flightlines3d(x, flightlines, z = "Z", ...)
```

Arguments

- `dtm` An object of the class RasterLayer
- `bg` The color for the background. Default is black.
- `clear_artifacts` logical. It is a known and documented issue that 3D visualisation with rgl displays artifacts. The points and lines are inaccurately positioned in the space and thus the rendering may look false or weird. This is because rgl computes with single precision float. To fix this, the objects are shifted to (0,0) to reduce the number of digits needed to represent their coordinates. The drawback is that the objects are not plotted at their actual coordinates.
- `...` Supplementary parameters for `surface3d` or `spheres3d`.
- `x` The output of the function plot used with a LAS object.
- `ttops` A SpatialPointsDataFrame that contains tree tops coordinates.
- `z` character. The name of the attribute that contains the height of the tree tops or of the flightlines.
- `flightlines` A SpatialPointsDataFrame that contains flightlines coordinates.
pmf

Ground Segmentation Algorithm

Description

This function is made to be used in lasground. It implements an algorithm for segmentation of
ground points based on a progressive morphological filter. This method is an implementation of
the Zhang et al. (2003) algorithm (see reference). Note that this is not a strict implementation of
Zhang et al. This algorithm works at the point cloud level without any rasterization process. The
morphological operator is applied on the point cloud, not on a raster. Also, Zhang et al. proposed
some formulas (eq. 4, 5 and 7) to compute the sequence of windows sizes and thresholds. Here,
these parameters are free and specified by the user. The function util_makeZhangParam enables
computation of the parameters according to the original paper.

Usage

pmf(ws, th)

Arguments

ws  numeric. Sequence of windows sizes to be used in filtering ground returns. The
    values must be positive and in the same units as the point cloud (usually meters,
    occasionally feet).

th  numeric. Sequence of threshold heights above the parameterized ground surface
to be considered a ground return. The values must be positive and in the same
units as the point cloud.
point_metrics

References


See Also

Other ground segmentation algorithms: csf()

Examples

LASfile <- system.file("extdata", "Topography.laz", package="lidR")
las <- readLAS(LASfile, select = "xyzrn")

ws <- seq(3, 12, 3)
th <- seq(0.1, 1.5, length.out = length(ws))

las <- lasground(las, pmf(ws, th))
plot(las, color = "Classification")

point_metrics  Point-based metrics

Description

Computes a series of user-defined descriptive statistics for a LiDAR dataset for each point. This function is very similar to grid_metrics but computes metrics for each point based on its k-nearest neighbours or its sphere neighbourhood.

Usage

point_metrics(las, func, k, r, xyz = TRUE, filter = NULL)

Arguments

las An object of class LAS
func formula. An expression to be applied to each cell (see section "Parameter func").
k integer. k-nearest neighbours
r numeric. radius of the neighborhood sphere (not supported yet).
xyz logical. Coordinates of each point are returned in addition to each metric. If filter = NULL coordinates are references to the original coordinates and do not occupy additional memory. If filter != NULL it obviously takes memory.
filter formula of logical predicates. Enables the function to run only on points of interest in an optimized way. See also examples.
Details

It is important to bear in mind that this function is very fast for the feature it provides i.e. mapping a user-defined function at the point level using optimized memory management. However, it is still computationally demanding.

To help users to get an idea of how computationally demanding this function is, let’s compare it to `grid_metrics`. Assuming we want to apply mean(Z) on a 1 km² tile with 1 point/m² with a resolution of 20 m (400 m² cells), then the function mean is called roughly 2500 times (once per cell). On the contrary, with `point_metrics`, mean is called 1000000 times (once per point). So the function is expected to be more than 400 times slower in this specific case (but it does not provide the same feature).

This is why the user-defined function is expected to be well optimized, otherwise it might drastically slow down this already heavy computation. See examples.

Last but not least, `grid_metrics()` relies on the `data.table` package to compute a user-defined function in each pixel. `point_metrics()` relies on a similar method but with a major difference: it does not rely on `data.table` and thus has not been tested over many years by thousands of people. Please report bugs, if any.

Parameter `func`

The function to be applied to each cell is a classical function (see examples) that returns a labeled list of metrics. For example, the following function f is correctly formed.

\[
f = \text{function}(x) \{ \text{list(mean} = \text{mean}(x), \text{max} = \text{max}(x))\}
\]

And could be applied either on the Z coordinates or on the intensities. These two statements are valid:

\[
\text{point_metrics}(\text{las, } \sim f(Z), \text{ k = 8})
\]
\[
\text{point_metrics}(\text{las, } \sim f(\text{Intensity}), \text{ k = 5})
\]

Everything that works in `grid_metrics` should also work in `point_metrics` but might be meaningless. For example, computing the quantile of elevation does not really make sense here.

See Also

Other metrics: `cloud_metrics()`, `grid_metrics()`, `hexbin_metrics()`, `tree_metrics()`, `voxel_metrics()`

Examples

```r
## Not run:
LASfile <- system.file("extdata", "Topography.laz", package="lidR")

# Read only 0.5 points/m² for the purposes of this example
las = readLAS(LASfile, filter = "-thin_with_grid 2")

# Computes the eigenvalues of the covariance matrix of the neighbouring
```
point_metrics

# points and applies a test on these values. This function simulates the
# 'shp_plane()' algorithm from 'lasdetectshape()'
plane_metrics1 = function(x,y,z, th1 = 25, th2 = 6) {
  xyz <- cbind(x,y,z)
  cov_m <- cov(xyz)
  eigen_m <- eigen(cov_m)$value
  is_planar <- eigen_m[2] > (th1*eigen_m[3]) && (th2*eigen_m[2]) > eigen_m[1]
  return(list(planar = is_planar))
}

# Apply a user-defined function
M <- point_metrics(las, ~plane_metrics1(X,Y,Z), k = 25)
#> Computed in 6.3 seconds

# We can verify that it returns the same as 'shp_plane'
las <- lasdetectshape(las, shp_plane(k = 25), "planar")
#> Computed in 0.1 second

all.equal(M$planar, las$planar)

# At this stage we can be clever and find that the bottleneck is
# the eigenvalue computation. Let's write a C++ version of it with
# Rcpp and RcppArmadillo
Rcpp::sourceCpp(code = "
#include <RcppArmadillo.h>
// [[Rcpp::depends(RcppArmadillo)]]
// [[Rcpp::export]]
SEXP eigen_values(arma::mat A) {
  arma::mat coeff;
  arma::mat score;
  arma::vec latent;
  arma::princomp(coeff, score, latent, A);
  return(Rcpp::wrap(latent));
}
"

plane_metrics2 = function(x,y,z, th1 = 25, th2 = 6) {
  xyz <- cbind(x,y,z)
  eigen_m <- eigen_values(xyz)
  is_planar <- eigen_m[2] > (th1*eigen_m[3]) && (th2*eigen_m[2]) > eigen_m[1]
  return(list(planar = is_planar))
}

M <- point_metrics(las, ~plane_metrics2(X,Y,Z), k = 25)
#> Computed in 0.5 seconds

all.equal(M$planar, las$planar)

# Here we can see that the optimized version is way better but is still 5 times slower
# because of the overhead of calling R functions and switching back and forth from R to C++.

# Use the filter argument to process only first returns
M1 <- point_metrics(las, ~plane_metrics2(X,Y,Z), k = 25, filter = ~ReturnNumber == 1)
dim(M1) # 13894 instead of 17182 previously.

# is a memory-optimized equivalent to:
first = lasfilterfirst(las)
M2 <- point_metrics(first, plane_metrics2(X,Y,Z), k = 25)
all.equal(M1, M2)

## End(Not run)

---

print
Summary and Print for LAS* objects

Description

Summary and Print for LAS* objects

Usage

print(x, ...)

## S4 method for signature 'LAS'
summary(object, ...)

## S4 method for signature 'LAS'
print(x)

## S4 method for signature 'LAScatalog'
summary(object, ...)

Arguments

... Unused

object, x A LAS* object

Value

NULL, used for its side-effect of printing information
Get or set the projection of a LAS* object

Description
Get or set the projection of a LAS* object with the function `projection`. Functions `epsg` and `wkt` are reserved for advanced users (see details).

Usage

```r
epsg(object, ...)
epsg(object) <- value
wkt(object, ...)
wkt(object) <- value
```

## S4 method for signature 'LASheader'

```r
projection(x, asText = TRUE)
```

## S4 replacement method for signature 'LASheader'

```r
epsg(object, ...)
epsg(object) <- value

## S4 method for signature 'LASheader'
wkt(object, ...)
wkt(object) <- value

## S4 replacement method for signature 'LAS'

```r
projection(x) <- value
```

## S4 method for signature 'LAS'

```r
epsg(object)
epsg(object) <- value

## S4 method for signature 'LAS'
wkt(object)
wkt(object) <- value
```
Arguments

object, x  An object of class LAS or eventually LASheader (regular users don’t need to manipulate LASheader objects).

...  Unused.

value  A CRS object or a proj4string string for function projection. An EPSG code as integer for function epsg. A WKT string for function wkt.

asText  logical. If TRUE, the projection is returned as text. Otherwise a CRS object is returned.

Details

There are two ways to store the CRS of a point cloud in a LAS file:

- Store an EPSG code (for LAS 1.0 to 1.4)
- Store a WKT string (for LAS 1.4)

On the other hand, all spatial R packages use a proj4string to store the CRS. This is why the CRS is duplicated in a LAS object. The information belongs within the header in a format that can be written in a LAS file and in the slot proj4string in a format that can be understood by R packages.

- projection<-. updates the CRS from a proj4string. It updates the header either with the EPSG code for LAS formats < 1.4 or with a WKT string for LAS format 1.4 and updates the proj4string slot. This function should always be preferred.
- epsg<-. updates the CRS from an EPSG code. It adds the EPSG code in the header and updates the proj4string slot.
- wkt<-. updates the CRS from a WKT string. It adds the WKT string in the header and updates the proj4string slot.
- projection: reads the proj4string from the proj4string slot.
- epsg: reads the epsg code from the header.
- wkt: reads the WKT string from the header.

Examples

LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
las <- readLAS(LASfile)

projection(las)

projection(las) <- crs
random

Point Cloud Decimation Algorithm

Description
This function is made to be used in `lasfilterdecimate`. It implements an algorithm that randomly removes points or pulses to reach the desired density over the whole area (see `area`).

Usage
`random(density, use_pulse = FALSE)`

Arguments
- `density`: numeric. The desired output density.
- `use_pulse`: logical. Decimate by removing random pulses instead of random points (requires running `laspulse` first).

See Also
Other point cloud decimation algorithms: `highest()`, `homogenize()`

Examples
```r
LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
las = readLAS(LASfile, select = "xyz")

# Reach a pulse density of 1 on the overall dataset
thinned1 = lasfilterdecimate(las, random(1))
plot(grid_density(las))
plot(grid_density(thinned1))
```

rbind.LAS

Merge LAS objects

Description
Merge LAS objects

Usage
```r
## S3 method for class 'LAS'
rbind(...)
```

Arguments
- `...`: LAS objects
Description

Reads .las or .laz files into an object of class LAS. If several files are read at once the returned LAS object is considered as one LAS file. The optional parameters enable the user to save a substantial amount of memory by choosing to load only the attributes or points of interest. The LAS formats 1.1 to 1.4 are supported. Point Data Record Format 0,1,2,3,5,6,7,8 are supported.

Usage

readLAS(files, select = "*", filter = "")

Arguments

files characters. Path(s) to one or several a file(s). Can also be a LAScatalog object.
select character. Read only attributes of interest to save memory (see details).
filter character. Read only points of interest to save memory (see details).

Details

Select: the 'select' argument specifies the data that will actually be loaded. For example, 'xyzia' means that the x, y, and z coordinates, the intensity and the scan angle will be loaded. The supported entries are t - gpstime, a - scan angle, i - intensity, n - number of returns, r - return number, c - classification, s - synthetic flag, k - keypoint flag, w - withheld flag, o - overlap flag (format 6+), u - user data, p - point source ID, e - edge of flight line flag, d - direction of scan flag, R - red channel of RGB color, G - green channel of RGB color, B - blue channel of RGB color, N - near-infrared channel. C - scanner channel (format 6+). Also numbers from 1 to 9 for the extra bytes data numbers 1 to 9. 0 enables all extra bytes to be loaded and '*' is the wildcard that enables everything to be loaded from the LAS file.
Note that x, y, z are implicit and always loaded. 'xyzia' is equivalent to 'ia'.

Filter: the 'filter' argument allows filtering of the point cloud while reading files. This is much more efficient than lasfilter in many ways. If the desired filters are known before reading the file, the internal filters should always be preferred. The available filters are those from LASlib and can be found by running the following command: rlas::lasfilterusage(). (see also rlas::read.las)

Value

A LAS object

Examples

LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
las = readLAS(LASfile)
las = readLAS(LASfile, select = "xyz")
las = readLAS(LASfile, select = "xyzi", filter = "-keep_first")
las = readLAS(LASfile, select = "xyziar", filter = "-keep_first -drop_z_below 0")

# Negation of attributes is also possible (all except intensity and angle)
las = readLAS(LASfile, select = "*-i -a")

---

**readLAScatalog**  
*Create an object of class LAScatalog*

---

**Description**

Create an object of class **LAScatalog** from a folder or a set of filenames. A LAScatalog is a representation of a set of las/laz files. A computer cannot load all the data at once. A LAScatalog is a simple way to manage all the files sequentially. Most functions from *lidR* can be used seamlessly with a LAScatalog using the internal LAScatalog processing engine. To take advantage of the LAScatalog processing engine the user must first adjust some processing options using the appropriated functions. Careful reading of the LAScatalog class documentation is required to use the LAScatalog class correctly.

catalog() is softly deprecated for readLAScatalog().

**Usage**

readLAScatalog(folder, progress = FALSE, ...)

catalog(folder, ...)

**Arguments**

- **folder**  
  string. The path of a folder containing a set of las/laz files. Can also be a vector of file paths.

- **progress**  
  boolean. Display a progress bar.

- **...**  
  Extra parameters to list.files. Typically 'recursive = TRUE'.

**Value**

A LAScatalog object

**Examples**

# A single file LAScatalog using data provided with the package
LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
ctg = readLAScatalog(LASfile)
plot(ctg)

## Not run:
ctg <- readLAScatalog("/path/to/a/folder/of/las/files")
# Internal engine will sequentially process chunks of size 500 x 500 m (clusters)
opt_chunk_size(ctg) <- 500

# Internal engine will align the 500 x 500 m chunks on x = 250 and y = 300
opt_alignment(ctg) <- c(250, 300)

# Internal engine will not display a progress estimation
opt_progress(ctg) <- FALSE

# Internal engine will not return results into R. Instead it will write results in files.
opt_output_files(ctg) <- "/path/to/folder/templated_filename_{XBOTTOM}_{ID}"

# More details in the documentation
help("LAScatalog-class", "lidR")
help("catalog_options_tools", "lidR")

## End(Not run)

---

**readLASHeader**

*Read a .las or .laz file header*

### Description

Reads a .las or .laz file header into an object of class `LASHeader`. This function strictly reads the header while the function `readLAS` can alter the header to fit the actual data loaded.

### Usage

```r
readLASHeader(file)
```

### Arguments

- **file**  
  characters. Path to one file.

### Value

A `LASHeader` object

### Examples

```r
LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
header = readLASHeader(LASfile)

print(header)
plot(header)

## Not run:
plot(header, mapview = TRUE)
## End(Not run)
```
rumple_index

Rumple Index of Roughness

Description

Computes the roughness of a surface as the ratio between its area and its projected area on the
ground. If the input is a gridded object (lasmetric or raster) the function computes the surfaces
using Jenness's algorithm (see references). If the input is a point cloud the function uses a Delaunay
triangulation of the points and computes the area of each triangle.

Usage

rumple_index(x, y = NULL, z = NULL, ...)

Arguments

x A 'RasterLayer' or a vector of x point coordinates.
y numeric. If x is a vector of coordinates: the associated y coordinates.
z numeric. If x is a vector of coordinates: the associated z coordinates.
... unused

Value

numeric. The computed Rumple index.

References


Examples

x = runif(20, 0, 100)
y = runif(20, 0, 100)

# Perfectly flat surface, rumple_index = 1
z = rep(10, 20)
rumple_index(x, y, z)

# Rough surface, rumple_index > 1
z = runif(20, 0, 10)
rumple_index(x, y, z)

# Rougher surface, rumple_index increases
z = runif(20, 0, 50)
rumple_index(x, y, z)

# Measure of roughness is scale-dependent
rumple_index(x, y, z)
rumple_index(x/10, y/10, z)

# Use with a canopy height model
LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
las = readLAS(LASfile)
chm = grid_canopy(las, 2, p2r())
rumple_index(chm)

---

sensor_tracking  
Reconstruct the trajectory of the LiDAR sensor using multiple returns

### Description

Use multiple returns to estimate the positioning of the sensor by computing the intersection in space of the line passing through the first and last returns. To work, this function requires a dataset where the 'gpstime', 'ReturnNumber', 'NumberOfReturns' and 'PointSourceID' attributes are properly populated, otherwise the output may be incorrect or weird. For LAScatalog processing it is recommended to use large chunks and large buffers (e.g. a swath width). The point cloud must not be normalized.

### Usage

```r
sensor_tracking(
  las,
  interval = 0.5,
  pmin = 50,
  extra_check = TRUE,
  thin_pulse_with_time = 0.001
)
```

### Arguments

- **las**: An object of class LAS or LAScatalog.
- **interval**: numeric. Interval used to bin the gpstime times and group the pulses to compute a position at a given timepoint t.
- **pmin**: integer. Minimum number of pulses needed to estimate a sensor position. For a given interval, the sensor position is not computed if the number of pulses is lower than pmin.
- **extra_check**: boolean. Datasets are rarely perfectly populated, leading to unexpected errors. Time-consuming checks of data integrity are performed. These checks can be skipped as they account for an important proportion of the computation time. See also section 'Tests of data integrity'.
- **thin_pulse_with_time**: numeric. In practice, it is useless to compute the position using all multiple returns. It is more computationally demanding but not necessarily more accurate. This keeps only one pulse every x seconds. Set to 0 to use all multiple returns.
Use 0 if the file has already been read with filter = "-thin_pulses_with_time 0.001".

Details

When multiple returns from a single pulse are detected, the sensor computes their positions as being in the center of the footprint and thus all aligned. Because of that behavior, a line drawn between and beyond those returns must cross the sensor. Thus, several consecutive pulses emitted in a tight interval (e.g. 0.5 seconds) can be used to approximate an intersection point in the sky that corresponds to the sensor position given that the sensor carrier hasn’t moved much during this interval. A weighted least squares method gives an approximation of the intersection by minimizing the squared sum of the distances between the intersection point and all the lines.

Value

A SpatialPointsDataFrame with the Z elevation stored in the table of attributes. Information about the time interval and the number of pulses used to find the points is also in the table of attributes.

Test of data integrity

In theory, sensor tracking is a simple problem to solve as long as each pulse is properly identified from a well-populated dataset. In practice, many problems may arise from datasets that are populated incorrectly. Here is a list of problem that may happen. Those with a * denote problems already encountered and internally checked to remove weird points:

- ‘gpstime’ does not record the time at which pulses were emitted and thus pulses are not identifiable
- *A pulse (two or more points that share the same gpstime) is made of points from different flightlines (different PointSourceID). This is impossible and denotes an improperly populated PointSourceID attribute.
- ‘ReturnNumber’ and ‘NumberOfReturns’ are wrongly populated with either some Return-Number > NumberOfReturn or several first returns by pulses

For a given time interval, when weird points are not filtered, the position is not computed for this interval.

Working with a LAScatalog

This section appears in each function that supports a LAScatalog as input.

In lidR when the input of a function is a LAScatalog the function uses the LAScatalog processing engine. The user can modify the engine options using the available options. A careful reading of the engine documentation is recommended before processing LAScatalogs. Each lidR function should come with a section that documents the supported engine options.

The LAScatalog engine supports .lax files that significantly improve the computation speed of spatial queries using a spatial index. Users should really take advantage a .lax files, but this is not mandatory.
Supported processing options

Supported processing options for a LAScatalog (in bold). For more details see the LAScatalog engine documentation:

- **chunk size**: How much data is loaded at once.
- **chunk buffer**: Mandatory to get a continuous output without edge effects. The buffer is always removed once processed and will never be returned either in R or in files.
- **chunk alignment**: Align the processed chunks.
- **progress**: Displays a progression estimation.
- **output_files**: Saving intermediate results is disabled in 'sensor_tracking' because the output must be post-processed as a whole.
- **laz_compression**: write las or laz files
- **select**: is not supported. It is set by default to "xyzrntp"
- **filter**: Read only points of interest. By default it uses "-drop_single" and "-thin_pulses_with_time" to reduce the number of points loaded.

Author(s)

Jean-Francois Bourdon & Jean-Romain Roussel

Examples

```r
# A valid file properly populated
LASfile <- system.file("extdata", "Topography.laz", package="lidR")
las = readLAS(LASfile)
plot(las)

# pmin = 15 because it is an extremely tiny file
# strongly decimated to reduce its size. There are
# actually few multiple returns
flightlines <- sensor_tracking(las, pmin = 15)

plot(las@header)
plot(flightlines, add = TRUE)

x <- plot(las)
add_flightlines3d(x, flightlines, radius = 10)

# Load only the data actually useful
las <- readLAS(LASfile,
   select = "xyzrntp",
   filter = "-drop_single -thin_pulses_with_time 0.001")
flightlines <- sensor_tracking(las)

x <- plot(las)
add_flightlines3d(x, flightlines, radius = 10)

## Not run:
# With a LAScatalog "-drop_single" and "-thin_pulses_with_time"
```
# are used by default
c tg = readLAScatalog("folder/")
flightlines <- sensor_tracking(ctg)
plot(flightlines)

## End(Not run)

set_lidr_threads Set or get number of threads that lidR should use

Description

Set and get number of threads to be used in lidR functions that are parallelized with OpenMP. Default value 0 means to utilize all CPU available. get_lidr_threads() returns the number of threads that will be used. This affects lidR package but also the data.table package by internally calling setDTthreads because several functions of lidR rely on data.table but it does not change R itself or other packages using OpenMP.

Usage

set_lidr_threads(threads)

get_lidr_threads()

Arguments

threads An integer >= 0. Default 0 means use all CPU available and leave the operating system to multi task.

See Also

lidR-parallelism

shape_detection Algorithms for shape detection of the local point neighborhood

Description

These functions are made to be used in lasdetectshape. They implement algorithms for local neighborhood shape estimation.

Usage

shp_plane(th1 = 25, th2 = 6, k = 8)

shp_hplane(th1 = 25, th2 = 6, th3 = 0.98, k = 8)

shp_line(th1 = 10, k = 8)
Arguments

- th1, th2, th3 numeric. Threshold values (see details)
- k integer. Number of neighbours used to estimate the neighborhood.

Details

In the following, $a_1, a_2, a_3$ denote the eigenvalues of the covariance matrix of the neighbouring points in ascending order. $th_1, th_2, th_3$ denote a set of threshold values. Points are labelled TRUE if they meet the following criteria. FALSE otherwise.

**shp_plane** Detection of plans based on criteria defined by Limberger & Oliveira (2015) (see references). A point is labelled TRUE if the neighborhood is approximately planar, that is:

$$a_2 > (th_1 \times a_1)\text{and}(th_2 \times a_2) > a_3$$

**shp_hplane** The same as 'plane' but with an extra test on the orientation of the Z vector of the principal components to test the horizontality of the surface.

$$a_2 > (th_1 \times a_1)\text{and}(th_2 \times a_2) > a_3\text{and}\left|Z\right| > th_3$$

In theory $\left|Z\right|$ should be exactly equal to 1. In practice 0.98 or 0.99 should be fine

**shp_line** Detection of lines inspired by the Limberger & Oliveira (2015) criterion. A point is labelled TRUE if the neighborhood is approximately linear, that is:

$$th_1 \times a_2 < a_3\text{and}th_1 \times a_1 < a_3$$

References


---

**silva2016**

*Individual Tree Segmentation Algorithm*

Description

This function is made to be used in `lastrees`. It implements an algorithm for tree segmentation based on the Silva et al. (2016) article (see reference). This is a simple method based on seed + voronoi tesselation (equivalent to nearest neighbour). This algorithm is implemented in the package `rLiDAR`. This version is not the version from `rLiDAR`. It is code written from the original article by the lidR authors and is considerably (between 250 and 1000 times) faster.

Usage

`silva2016(chm, treetops, max_cr_factor = 0.6, exclusion = 0.3, ID = "treeID")`
Arguments

chm  RasterLayer. Image of the canopy. Can be computed with grid_canopy or read from an external file.

treetops  SpatialPointsDataFrame. Can be computed with tree_detection or read from an external shapefile.

max_cr_factor  numeric. Maximum value of a crown diameter given as a proportion of the tree height. Default is 0.6, meaning 60% of the tree height.

exclusion  numeric. For each tree, pixels with an elevation lower than exclusion multiplied by the tree height will be removed. Thus, this number belongs between 0 and 1.

ID  character. If the SpatialPointsDataFrame contains an attribute with the ID for each tree, the name of this column. This way, original IDs will be preserved. If there is no such data trees will be numbered sequentially.

Details

Because this algorithm works on a CHM only there is no actual need for a point cloud. Sometimes the user does not even have the point cloud that generated the CHM. lidR is a point cloud-oriented library, which is why this algorithm must be used in lastrees to merge the result into the point cloud. However, the user can use this as a stand-alone function like this:

```r
chm = raster("file/to/a/chm/")
ttops = tree_detection(chm, lmf(3))
crowns = silva2016(chm, ttops)()
```

References


See Also

Other individual tree segmentation algorithms: dalponte2016(), li2012(), watershed()

Other raster based tree segmentation algorithms: dalponte2016(), watershed()

Examples

```r
LASfile <- system.file("extdata", "MixedConifer.laz", package="lidR")
las <- readLAS(LASfile, select = "xyz", filter = "-drop_z_below 0")
col <- pastel.colors(200)

chm <- grid_canopy(las, res = 0.5, p2r(0.3))
ker <- matrix(1,3,3)
chm <- raster::focal(chm, w = ker, fun = mean, na.rm = TRUE)

ttops <- tree_detection(chm, lmf(4, 2))
```
`las <- lastrees(las, silva2016(chm, ttops))`
`plot(las, color = "treeID", colorPalette = col)`

### stdmetrics

Predefined standard metrics functions

#### Description

Predefined functions computable at pixel level (`grid_metrics`), hexagonal cell level (`hexbin_metrics`), point cloud level (`cloud_metrics`), tree level (`tree_metrics`) voxel level (`voxel_metrics`) and point level (`point_metrics`). Each function comes with a convenient shortcuts for lazy coding. The lidR package aims to provide an easy way to compute user-defined metrics rather than to provide them. However, for efficiency and to save time, a set of standard metrics has been predefined (see details).

#### Usage

- `stdmetrics(x, y, z, i, rn, class, dz = 1, th = 2)`
- `stdmetrics_z(z, dz = 1, th = 2)`
- `stdmetrics_i(i, z = NULL, class = NULL, rn = NULL)`
- `stdmetrics_rn(rn, class = NULL)`
- `stdmetrics_pulse(pulseID, rn)`
- `stdmetrics_ctrl(x, y, z)`
- `stdtreemetrics(x, y, z)`
- `stdshapemetrics(x, y, z)`

`.stdmetrics`  
`.stdmetrics_z`  
`.stdmetrics_i`  
`.stdmetrics_rn`  
`.stdmetrics_pulse`  
`.stdmetrics_ctrl`  
`.stdtreemetrics`  
`.stdshapemetrics`
Arguments

- **x, y, z, i**: Coordinates of the points, Intensity
- **rn, class**: ReturnNumber, Classification
- **dz**: numeric. Layer thickness metric entropy
- **th**: numeric. Threshold for metrics pzabovex. Can be a vector to compute with several thresholds.
- **pulseID**: The number referencing each pulse

Format

An object of class `formula` of length 2.

Details

The function names, their parameters and the output names of the metrics rely on a nomenclature chosen for brevity:

- **z**: refers to the elevation
- **i**: refers to the intensity
- **rn**: refers to the return number
- **q**: refers to quantile
- **a**: refers to the ScanAngleRank or ScanAngle
- **n**: refers to a number (a count)
- **p**: refers to a percentage

For example the metric named `zq60` refers to the elevation, quantile, 60 i.e. the 60th percentile of elevations. The metric `pground` refers to a percentage. It is the percentage of points classified as ground. The function `stdmetric_i` refers to metrics of intensity. A description of each existing metric can be found on the `lidR wiki` page.

Some functions have optional parameters. If these parameters are not provided the function computes only a subset of existing metrics. For example, `stdmetrics_i` requires the intensity values, but if the elevation values are also provided it can compute additional metrics such as cumulative intensity at a given percentile of height.

Each function has a convenient associated variable. It is the name of the function, with a dot before the name. This enables the function to be used without writing parameters. The cost of such a feature is inflexibility. It corresponds to a predefined behavior (see examples)

- **stdmetrics** is a combination of `stdmetrics_ctrl` + `stdmetrics_z` + `stdmetrics_i` + `stdmetrics_rn`
- **stdtreemetrics** is a special function that works with `tree_metrics`. Actually, it won’t fail with other functions but the output makes more sense if computed at the individual tree level.
- **stdshapemetrics** is a set of eigenvalue based feature described in Lucas et al, 2019 (see references).
References


See Also

cloud_metrics grid_metrics grid_hexametrics grid_metrics3d tree_metrics point_metrics

Examples

```r
LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
las = readLAS(LASfile, select = "+")

# All the predefined metrics
m1 = grid_metrics(las, ~stdmetrics(X,Y,Z,Intensity,ReturnNumber,Classification,dz=1))

# Convenient shortcut
m2 = grid_metrics(las, .stdmetrics)

# Basic metrics from intensities
m3 = grid_metrics(las, ~stdmetrics_i(Intensity))

# All the metrics from intensities
m4 = grid_metrics(las, ~stdmetrics_i(Intensity, Z, Classification, ReturnNumber))

# Convenient shortcut for the previous example
m5 = grid_metrics(las, .stdmetrics_i)

# Compute the metrics only on first return
first = lasfilterfirst(las)
m6 = grid_metrics(first, .stdmetrics_z)

# Compute the metrics with a threshold at 2 meters
over2 = lasfilter(las, Z > 2)
m7 = grid_metrics(over2, .stdmetrics_z)

# Works also with cloud_metrics and hexbin_metrics
m8 = cloud_metrics(las, .stdmetrics)
m9 = hexbin_metrics(las, .stdmetrics)

# Combine some predefined function with your own new metrics
# Here convenient shortcuts are no longer usable.
myMetrics = function(z, i, rn) {
    first = rn == 1L
    zfirst = z[first]
    nfirst = length(zfirst)
    above2 = sum(z > 2)
    x = above2/nfirst*100
}
```
# User's metrics
metrics = list(
    above2aboven1st = x, # Num of returns above 2 divided by num of 1st returns
    zimean = mean(z*i), # Mean products of z by intensity
    zsqmean = sqrt(mean(z^2)) # Quadratic mean of z
)

# Combined with standard metrics
return( c(metrics, stdmetrics_z(z)) )

m10 = grid_metrics(las, ~myMetrics(Z, Intensity, ReturnNumber))

# Users can write their own convenient shortucts like this:
.myMetrics = ~myMetrics(Z, Intensity, ReturnNumber)

m11 = grid_metrics(las, .myMetrics)

---

## Spatial Interpolation Algorithm

### Description
This function is made to be used in `grid_terrain` or `lasnormalize`. It implements an algorithm for spatial interpolation. Spatial interpolation is based on a Delaunay triangulation, which performs a linear interpolation within each triangle. There are usually a few points outside the convex hull, determined by the ground points at the very edge of the dataset, that cannot be interpolated with a triangulation. Extrapolation is done using the nearest neighbour approach.

### Usage
```
tin()
```

### See Also
Other spatial interpolation algorithms: `knnidw()`, `kriging()`

### Examples
```r
LASfile <- system.file("extdata", "Topography.laz", package="lidR")
las = readLAS(LASfile)

# plot(las)
dtm = grid_terrain(las, algorithm = tin())
plot(dtm, col = terrain.colors(50))
plot_dtm3d(dtm)
```
Individual tree detection function that find the position of the trees using several possible algorithms.

Usage

\[
\text{treeDetection}(\text{las}, \text{algorithm})
\]

Arguments

- **las**: An object of class LAS or LAScatalog. Can also be a RasterLayer representing a canopy height model, in which case it is processed like a regularly-spaced point cloud.
- **algorithm**: An algorithm for individual tree detection. lidR has: lmf and manual. More experimental algorithms may be found in the package lidRplugins.

Value

A SpatialPointsDataFrame with an attribute Z for the tree tops and treeID with an individual ID for each tree.

Supported processing options

Supported processing options for a LAScatalog (in bold). For more details see the LAScatalog engine documentation:

- **chunk size**: How much data is loaded at once.
- **chunk buffer**: Mandatory to get a continuous output without edge effects. The buffer is always removed once processed and will never be returned either in R or in files.
- **chunk alignment**: Align the processed chunks.
- **progress**: Displays a progression estimation.
- **output files**: Supported templates are \{XLEFT\}, \{XRIGHT\}, \{YBOTTOM\}, \{YTOP\}, \{XCENTER\}, \{YCENTER\} \{ID\} and, if chunk size is equal to 0 (processing by file), \{ORIGINALFILENAME\}.
- **select**: Load only attributes of interest.
- **filter**: Read only points of interest.

Examples

```r
LASfile <- system.file("extdata", "MixedConifer.laz", package="lidR")
las <- readLAS(LASfile, select = "xyz", filter = "-drop_z_below 0")

ttops <- tree_detection(las, lmf(ws = 5))

x = plot(las)
add_treetops3d(x, ttops)
```
**tree_hulls**  
*Compute the hull of each tree.*

**Description**

Compute the hull of each segmented tree. The hull can be convex, concave or a bounding box (see details and references).

**Usage**

```r
library(lidR)

library(raster)

# Load example data
las <- raster::readRaster("")

tree_hulls(
  las,
  type = c("convex", "concave", "bbox"),
  concavity = 3,
  length_threshold = 0,
  func = NULL,
  attribute = "treeID"
)
```

**Arguments**

- **las**: An object of class LAS or LAScatalog.
- **type**: character. Hull type. Can be 'convex', 'concave' or 'bbox'.
- **concavity**: numeric. If type = "concave", a relative measure of concavity. 1 results in a relatively detailed shape, Infinity results in a convex hull.
- **length_threshold**: numeric. If type = "concave", when a segment length is below this threshold, no further detail is added. Higher values result in simpler shapes.
- **func**: formula. An expression to be applied to each tree. It works like in grid_metrics voxel_metrics or tree_metrics and computes, in addition to the hulls a set of metrics for each tree.
- **attribute**: character. The attribute where the ID of each tree is stored. In lidR, the default is "treeID".

**Details**

The concave hull method under the hood is described in Park & Oh (2012). The function relies on the concaveman function which itself is a wrapper around Vladimir Agafonking’s implementation.

**Value**

A SpatialPolygonsDataFrame. If a tree has less than 4 points it is not considered.
**Working with a LAScatalog**

This section appears in each function that supports a LAScatalog as input.

In *lidR* when the input of a function is a LAScatalog the function uses the LAScatalog processing engine. The user can modify the engine options using the available options. A careful reading of the engine documentation is recommended before processing LAScatalogs. Each *lidR* function should come with a section that documents the supported engine options.

The LAScatalog engine supports .lax files that significantly improve the computation speed of spatial queries using a spatial index. Users should really take advantage a .lax files, but this is not mandatory.

**Supported processing options**

Supported processing options for a LAScatalog (in bold). For more details see the LAScatalog engine documentation:

- **chunk size**: How much data is loaded at once.
- **chunk buffer**: Mandatory to get a continuous output without edge effects. The buffer is always removed once processed and will never be returned either in R or in files.
- **chunk alignment**: Align the processed chunks.
- **progress**: Displays a progression estimation.
- **output files**: Supported templates are `{XLEFT}`, `{XRIGHT}`, `{YBOTTOM}`, `{YTOP}`, `{XCENTER}`, `{YCENTER}` `{ID}` and, if chunk size is equal to 0 (processing by file), `{ORIGINALFILENAME}`.
- **select**: Load only attributes of interest.
- **filter**: Read only points of interest.

**References**


**Examples**

```r
LASfile <- system.file("extdata", "MixedConifer.laz", package="lidR")
las = readLAS(LASfile, select = "xyz0", filter = "-drop_z_below 0")

# NOTE: This dataset is already segmented
# plot(las, color = "treeID", colorPalette = pastel.colors(200))

# Only the hulls
convex_hulls = tree_hulls(las)
plot(convex_hulls)

# The Hulls + some user-defined metrics
convex_hulls = tree_hulls(las, func = ~list(Zmax = max(Z)))
```
tree_metrics

Compute metrics for each tree

Description

Once the trees are segmented, i.e. attributes exist in the point cloud that reference each tree, computes a set of user-defined descriptive statistics for each individual tree. This is the "tree version" of grid_metrics.

Usage

tree_metrics(las, func = ~max(Z), attribute = "treeID")

Arguments

- **las**: An object of class LAS or LAScatalog.
- **func**: formula. An expression to be applied to each tree. It works like in grid_metrics voxel_metrics or tree_hulls and computes, in addition to tree locations a set of metrics for each tree.
- **attribute**: character. The column name of the attribute containing tree IDs. Default is "treeID"

Details

By default the function computes the xyz-coordinates of the highest point of each tree and uses xy as tree coordinates in SpatialPointsDataFrame. z is stored in the table of attributes along with the id of each tree. All the other attributes are user-defined attributes:

The following existing functions contain a small set of pre-defined metrics:

- stdmetrics_tree

Users must write their own functions to create their own metrics. tree_metrics will dispatch the LiDAR data for each segmented tree in the user-defined function. Functions are defined without the need to consider each segmented tree i.e. only the point cloud (see examples).
Value
A SpatialPointsDataFrame that references the xy-position with a table of attributes that associates the z-elevation (highest points) of the trees and the id of the trees, plus the metrics defined by the user.

Working with a LAScatalog
This section appears in each function that supports a LAScatalog as input.

In lidR when the input of a function is a LAScatalog the function uses the LAScatalog processing engine. The user can modify the engine options using the available options. A careful reading of the engine documentation is recommended before processing LAScatalogs. Each lidR function should come with a section that documents the supported engine options.

The LAScatalog engine supports .lax files that significantly improve the computation speed of spatial queries using a spatial index. Users should really take advantage a .lax files, but this is not mandatory.

Supported processing options
Supported processing options for a LAScatalog (in bold). For more details see the LAScatalog engine documentation:

- **chunk size**: How much data is loaded at once.
- **chunk buffer**: Mandatory to get a continuous output without edge effects. The buffer is always removed once processed and will never be returned either in R or in files.
- **chunk alignment**: Align the processed chunks.
- **progress**: Displays a progression estimation.
- **output files**: Supported templates are {XLEFT}, {XRIGHT}, {YBOTTOM}, {YTOP}, {XCENTER}, {YCENTER} {ID} and, if chunk size is equal to 0 (processing by file), {ORIGINALFILENAME}.
- **select**: Load only attributes of interest.
- **filter**: Read only points of interest.

See Also
Other metrics: cloud_metrics(), grid_metrics(), hexbin_metrics(), point_metrics(), voxel_metrics()

Examples
LASfile <- system.file("extdata", "MixedConifer.laz", package="lidR")
las = readLAS(LASfile, filter = "-drop_z_below 0")
# NOTE: This dataset is already segmented
# plot(las, color = "treeID", colorPalette = pastel.colors(200))
# Default computes only Z max
util_makeZhangParam

Parameters for progressive morphological filter

Description

The function *lasground* with the progressive morphological filter allows for any sequence of parameters. This function enables computation of the sequences using equations (4), (5) and (7) from Zhang et al. (see reference and details).

Usage

```r
util_makeZhangParam(
  b = 2,
  dh0 = 0.5,
  dhmax = 3,
  s = 1,
  max_ws = 20,
  exp = FALSE
)
```

Arguments

- `b` numeric. This is the parameter $b$ in Zhang et al. (2003) (eq. 4 and 5).
- `dh0` numeric. This is $dh_0$ in Zhang et al. (2003) (eq. 7).
- `dhmax` numeric. This is $dh_{max}$ in Zhang et al. (2003) (eq. 7).
- `s` numeric. This is $s$ in Zhang et al. (2003) (eq. 7).
max_ws numeric. Maximum window size to be used in filtering ground returns. This limits the number of windows created.

exp logical. The window size can be increased linearly or exponentially (eq. 4 or 5).

Details

In the original paper the windows size sequence is given by eq. 4 or 5:

\[ w_k = 2^{kb} + 1 \]

or

\[ w_k = 2^{b^k} + 1 \]

In the original paper the threshold sequence is given by eq. 7:

\[ th_k = s \times (w_k - w_{k-1}) \times c + th_0 \]

Because the function lasground applies the morphological operation at the point cloud level the parameter \( c \) is set to 1 and cannot be modified.

Value

A list with two components: the windows size sequence and the threshold sequence.

References


Examples

\[ p = \text{util_makeZhangParam()} \]

---

VCI Vertical Complexity Index

Description

A fixed normalization of the entropy function (see references)

Usage

\[ \text{VCI}(z, \text{zmax}, \text{by} = 1) \]
**voxel_metrics**

Voxelize the space and compute metrics for each voxel

**Description**

This is a 3D version of `grid_metrics`. It creates a 3D matrix of voxels with a given resolution. It creates a voxel from the cloud of points if there is at least one point in the voxel. For each voxel the function allows computation of one or several derived metrics in the same way as the `grid_metrics` functions. The function will dispatch the LiDAR data for each voxel in the user’s function (see `grid_metrics`).

**Usage**

```r
go
voxel_metrics(las, func, res = 1)
```

**Arguments**

- `z` vector of z coordinates
- `zmax` numeric. Used to turn the function `entropy` to the function `vci`
- `by` numeric. The thickness of the layers used (height bin)

**Value**

A number between 0 and 1

**References**


**See Also**

`entropy`

**Examples**

```r
go
z = runif(10000, 0, 10)
VCI(z, by = 1, zmax = 20)
```

```r
go
z = abs(rnorm(10000, 10, 1))
# expected to be closer to 0.
VCI(z, by = 1, zmax = 20)
```
Arguments

- las: An object of class LAS.
- func: formula. An expression to be applied to each voxel (see also grid_metrics).
- res: numeric. The resolution of the voxels. \( \text{res} = 1 \) for a 1x1x1 cubic voxels. Optionally \( \text{res} = c(1,2) \) for non-cubic voxels (1x1x2 cuboid voxel).

Value

It returns a data.table containing the metrics for each voxel. The table has the class lasmetrics3d enabling easier plotting.

See Also

Other metrics: cloud_metrics(), grid_metrics(), hexbin_metrics(), point_metrics(), tree_metrics()

Examples

```r
LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
las = readLAS(LASfile)

# Cloud of points is voxelized with a 3-meter resolution and in each voxel
# the number of points is computed.
voxel_metrics(las, ~length(Z), 3)

# Cloud of points is voxelized with a 3-meter resolution and in each voxel
# the mean scan angle of points is computed.
voxel_metrics(las, ~mean(Intensity), 3)

## Not run:
# Define your own metric function
myMetrics = function(i)
{
  ret = list(
    npoints = length(i),
    imean = mean(i)
  )

  return(ret)
}

voxels = voxel_metrics(las, ~myMetrics(Intensity), 3)

plot(voxels, color = "imean", trim = 100)
# etc.

## End(Not run)
```
Description

This function is made to be used in lastrees. It implements an algorithm for tree segmentation based on a watershed or a marker-controlled watershed.

- **Simple watershed** is based on the bioconductor package EBIimage. You need to install this package to run this method (see its [github page](https://github.com/EBIimage/EBImage)). Internally, the function EBImage::watershed is called.

- **Marker-controlled watershed** is based on the imager package and has been removed because imager is an orphaned package.

Usage

```r
crown = watershed(chm, th_tree = 2, tol = 1, ext = 1)
mcwatershed(chm, treetops, th_tree = 2, ID = "treeID")
```

Arguments

- `chm` RasterLayer. Image of the canopy. Can be computed with `grid_canopy` or read from an external file.
- `th_tree` numeric. Threshold below which a pixel cannot be a tree. Default is 2.
- `tol` numeric. Tolerance see ?EBImage::watershed.
- `ext` numeric. see ?EBImage::watershed.
- `treetops` SpatialPointsDataFrame. Can be computed with `tree_detection` or read from an external shapefile.
- `ID` character. If the SpatialPointsDataFrame contains an attribute with the ID for each tree, the name of this column. This way, original IDs will be preserved. If there is no such data trees will be numbered sequentially.

Details

Because this algorithm works on a CHM only there is no actual need for a point cloud. Sometimes the user does not even have the point cloud that generated the CHM. lidR is a point cloud-oriented library, which is why this algorithm must be used in lastrees to merge the result into the point cloud. However, the user can use this as a stand-alone function like this:

```r
chm = raster("file/to/a/chm/")
ttops = tree_detection(chm, lmf(3))
crowns = watershed(chm)()
```
See Also

Other individual tree segmentation algorithms: `dalponte2016()`, `li2012()`, `silva2016()`
Other raster based tree segmentation algorithms: `dalponte2016()`, `silva2016()`

Examples

```r
LASfile <- system.file("extdata", "MixedConifer.laz", package="lidR")
las <- readLAS(LASfile, select = "xyz", filter = "-drop_z_below 0")
col <- pastel.colors(250)

chm <- grid_canopy(las, res = 0.5, p2r(0.3))
k <- matrix(1,3,3)
chm <- raster::focal(chm, w = k, fun = mean, na.rm = TRUE)
las <- lastrees(las, watershed(chm))

plot(las, color = "treeID", colorPalette = col)
```

Description

This function is made to be used in lassnags. It implements an algorithms for snags segmentation based on Wing et al (2015) (see references). This is an automated filtering algorithm that utilizes three dimensional neighborhood lidar point-based intensity and density statistics to remove lidar points associated with live trees and retain lidar points associated with snags.

Usage

```r
wing2015(
  neigh_radii = c(1.5, 1, 2),
  low_int_thrsh = 50,
  uppr_int_thrsh = 170,
  pt_den_req = 3,
  BBPRthrsh_mat = NULL
)
```

Arguments

- `neigh_radii` numeric. A vector of three radii used in quantifying local-area centered neighborhoods. See Wing et al. (2015) reference page 171 and Figure 4. Defaults are 1.5, 1, and 2 for the sphere, small cylinder and large cylinder neighborhoods, respectively.
Details

Note that this algorithm strictly performs a classification based on user input while the original publication's methods also included a segmentation step and some pre- (filtering for first and single returns only) and post-process (filtering for only the snag classified points prior to segmentation) tasks which are now expected to be performed by the user. Also, this implementation may have some differences compared with the original method due to potential mis-interpretation of the Wing et al. manuscript, specifically Table 2 where they present four groups of conditional assessments with their required neighborhood point density and average BBPR values (BBPR = branch and bole point ratio; PDR = point density requirement).

This algorithm attributes each point in the point cloud (snagCls column) into the following five snag classes:

- 0: live tree - not a snag
- 1: general snag - the broadest range of snag point situations
- 2: small snag - isolated snags with lower point densities
- 3: live crown edge snag - snags located directly adjacent or intermixing with live trees crowns
- 4: high canopy cover snag - snags protruding above the live canopy in dense conditions (e.g., canopy cover >= 55%).

The current implementation is known to use a large amount of memory for storing the N x k integer matrix returning the near neighbor indices for each point in the point cloud. Improvements are possible in future package versions.

Author(s)

Implementation by Andrew Sánchez Meador & Jean-Romain Roussel

References

writeLAS

Write a .las or .laz file

Description

Write a LAS object into a binary .las or .laz file (compression specified in filename)

Usage

writeLAS(las, file)

Arguments

<table>
<thead>
<tr>
<th>Argument</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>las</td>
<td>an object of class LAS.</td>
</tr>
<tr>
<td>file</td>
<td>character. A character string naming an output file.</td>
</tr>
</tbody>
</table>

Value

Nothing. This function is used for its side-effect of writing a file.
\texttt{\$<-,LAS-method}

### Examples

```r
LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
las = readLAS(LASfile)
subset = lasclipRectangle(las, 684850, 5017850, 684900, 5017900)
writeLAS(subset, tempfile(fileext = ".laz"))
```

\texttt{\$<-,LAS-method} \textit{Inherited but modified methods from sp}

### Description

LAS\* objects are \textit{Spatial} objects so they inherit several methods from \textit{sp}. However, some have modified behaviors to prevent some irrelevant modifications. Indeed, a LAS\* object cannot contain anything, as the content is restricted by the LAS specifications. If a user attempts to use one of these functions inappropriately an informative error will be thrown.

### Usage

```r
## S4 replacement method for signature 'LAS'
x$name <- value

## S4 replacement method for signature 'LAS,ANY,missing'
x[[i, j]] <- value

## S4 method for signature 'LAScatalog,ANY,ANY'
x[i, j, ..., drop = TRUE]

## S4 replacement method for signature 'LAScatalog,ANY,ANY'
x[[i, j]] <- value

## S4 replacement method for signature 'LAScatalog'
x$name <- value
```

### Arguments

- **x**: A LAS\* object
- **name**: A literal character string or a name (possibly backtick quoted).
- **value**: typically an array-like R object of a similar class as \( x \).
- **i**: string, name of elements to extract or replace.
- **j**: Unused.
- **...**: Unused
- **drop**: Unused
Examples

## Not run:
LASfile <- system.file("extdata", "Megaplot.laz", package="lidR")
las = readLAS(LASfile)

las$Z = 2L
las["Z"] = 1:10
las$NewCol = 0
las[["NewCol"]]] = 0

## End(Not run)
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