



LiAir H600

UAV LiDAR System

User Guide

GreenValley International Inc.

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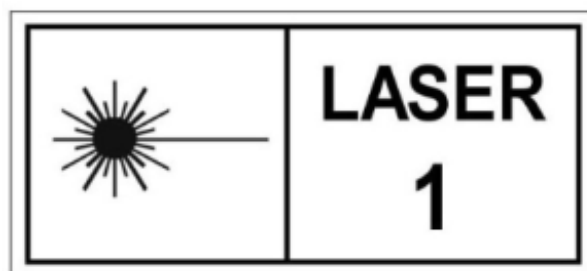
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1 User Instructions

⚠ Safety Precautions

1. LiAir H600 system uses Class 1 (IEC60825-1:2014) eye-safe laser sensors. If you have any concerns, please contact GVI for details.



2. Please read this manual carefully before operating the system, and the system operator must be at least 18 years old.
3. Please stop using the system if you hear noticeable noises, warnings, or while the device is damaged. Contact the manufacturer's technicians for maintenance in time. Forcible use may cause permanent damage to the system.
4. Strictly follow the tutorials, advises, warnings, and other cautions included in this user guide as well as other documents provided by GVI.
5. Do NOT use any power supply outside the specified voltage range (14~24V, 2.34A@24VDC). Incorrect voltage supply may cause permanent damages to the integrated instruments and other hazards. Damage caused by the use of an unauthorized power supply is not covered by the Product Warranty.
6. Keep the power, USB, network and other connector ports clean and dry, and do not insert other objects other than the connector.
7. Tampering with the product is strictly prohibited and will void the Product Warranty. Any repair, modification, or upgrade must be performed by GVI technician or authorized service provider.
8. This product is a high-precision mapping and surveying instrument that must be

handled with care. This product should be stored and transported in the protective case provided with the LiAir H600 at the time of purchase or in a protective case authorized for use by GVI.

9. When not in use, store LiAir H600 system and accessories in a cool and dry environment. Make sure the device is powered off when performing maintenance and cleaning.
10. The working temperature of this equipment is -20°C~50°C. Below/exceeding this temperature range, may cause wrong measurement results, data loss or equipment damage.
11. Before using the equipment, please ensure that the operating environment is far away from the source of electromagnetic interference.
12. There are corresponding specifications for battery use and storage. Please refer to the lithium battery use/storage specifications for details.
13. After the equipment is scrapped, please do not throw it directly into the trash can. It can be sent back to the manufacturer, and the manufacturer will handle it on your behalf.

GreenValley International Inc. reserves the right to explain the above terms.

GreenValley International Inc.

April 28, 2025

2 Product Introduction

The LiAir H600 is a next-generation lightweight, medium-range LiDAR scanning system developed by GreenValley International (GVI). It integrates compact mapping-grade LiDAR, proprietary high-precision inertial navigation, and a high-resolution mapping camera. The entire system weighs only 1.3 kg and can measure distances up to 800 meters. It is easily adaptable to small rotorcraft and fixed-wing aircraft, significantly enhancing endurance and operational efficiency. Paired with flight control software GreenValley and data post-processing software LiDAR360/LiPowerline, it provides an efficient one-stop solution for powerline inspection, forestry resource surveys, and emergency disaster assessment.



The LiAir H600 (shown above) mainly consists of three components: a LiDAR scanning system, an inertial navigation system, and a storage & control system.

The main components include:

1. Dynamic Differential GNSS Receiver: Used to measure the spatial position of the reference point for LiDAR signal emission.
2. Inertial Navigation Device: An attitude measurement equipment used to measure the attitude parameters of the main optical axis of the scanning device.

3. **Laser Scanning Head:** A laser ranging device used to measure the distance between the reference point of LiDAR signal emission and the ground laser footprint, which is the core component of the entire integrated system.
4. **Storage and Control System:** Used for data storage and device control, receiving signals transmitted from the ground station to the airborne unit, and managing functions such as parameter adjustment, data acquisition, and data download.
5. **Power System:** Used to supply power to the entire device.

Operating principle:

1. The LiDAR system employs the pulsed laser ranging (Time-of-Flight, TOF) method, which measures distance based on the flight time of the laser. The rangefinder records the timing information of the emitted and received pulses.
2. The system controls the device to collect data by receiving and executing commands sent by the hardware switch.
3. In the flight process, the system carries out the fusion and solution of the inertial navigation and laser data in real time. Powerlines and towers are recognized and extracted through AI algorithms. The drone is controlled to adjust its position and attitude in real time to track cables, turn over the towers, and take pictures of the towers or powerlines.
4. Then the raw data collected are stored in the TF card and copied to the local computer for processing after the collection is completed.
5. Finally, the LiGeoreference software is used to combine and georeference the position and angle information under the coordinate system of the LiDAR system with the POS data to obtain accurate geographic coordinates.

2.1 Technical Specifications

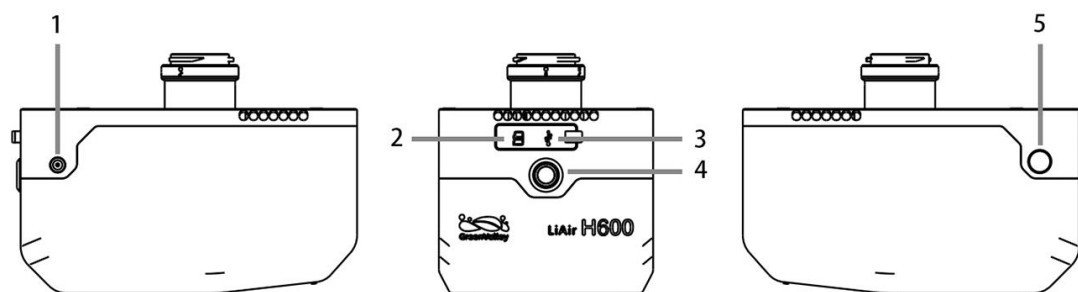
LiAir H600 System Parameters

Weight	1.3 kg
Scan Range (Sunny, Outdoor @100 klx)	267 m (reflectivity $\geq 10\%$) 750 m (reflectivity $\geq 80\%$)
Field of view	80°
Number of Returns	Unlimited waveform returns ^[1]
Data Frequency	100,000~550,000 pts/s
Camera pixels	26 MP
POS Attitude Accuracy (post-processing)	0.006°
POS Azimuth Accuracy (post-processing)	0.019°
Size	179×114×127.2 mm
Voltage	14~24V, 2.34A@24VDC
Power Consumption	About 50W
Operating Temperature	-20~50°C
Storage Temperature	-20~60°C
Protection Class	IP64
UAV Model	M300/M350 RTK
Display Console	GreenValley Flight Assistant
Data Georeferencing Software	LiGeoreference point cloud data solution software

[1]The theoretical maximum number of returns can only be achieved under specific conditions and

is constrained by the actual test scenario.

2.2 Product Structure



- 1— GNSS: Antenna port.
- 2— Memory card slot: With a built-in 256G TF card for data storage.
- 3— USB-C port: For the communication between the computer and the device for firmware upgrade and data download.
- 4— Switch button (ON/OFF) and indicator: The button is shared for power-on and project creation and display the working status of the device.
- 5— Power Port (PWR): Connect the power cable to power up the system.

Meaning of status indicator status:

LED	Color/Status	Description
ON/OFF	Flashing Red (Four Times a Second)	System is powered on and initializing
	Solid Green	System initialization completed
	Flashing Green (Once per second)	The project has been created, the inertial navigation data is being recorded, and the system is working normally.

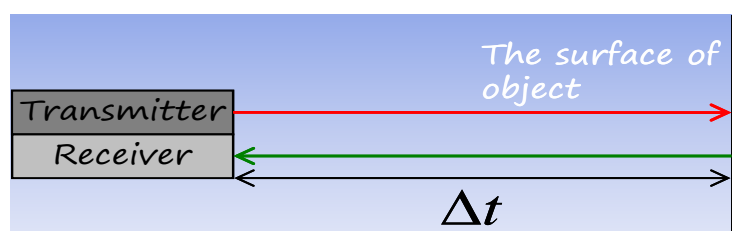
	Flashing Red (Once per Second)	The project has been created, the inertial navigation data is being recorded, and the system is working abnormally.
	Solid Red	<p>The system status is abnormal, the reasons include:</p> <ol style="list-style-type: none"> 1. TF card space is less than 15G 2. DJI M300/350 RTK aircraft PSDK module is not activated 3. IMU misalignment 4. Camera self-test fails 5. The laser scanner is not synchronized 6. Time not synchronized

2.3 System Compositions

2.3.1 Laser Scanner

The laser scanner is the core of the system. The LiDAR uses the laser as the emitting light source and the photoelectric detection sensor as the receiving element. According to the principle of laser ranging, the distance and angle are measured and recorded, so as to determine the azimuth information of the measured object.

The transmitter in the LiDAR emits a beam of ultra-short light pulses on the object and diffusely reflects back to the receiver. The speed of light is known, and the distance from the target object to the sensor is calculated by the flight time of the laser beam in the air.



LiDAR ranging equation:

$$S = \frac{1}{2} \times c \times \Delta t$$

Where: S is the distance from the sensor to the target; c is the light speed; and Δt is the round-trip time of the laser beam.

The LiAir H600 product integrates a surveying-grade laser with a field of view (FOV) of 80°.

Laser Scanner Parameters

Scanning Principle	Rotating Motor
Number of Channels	1
Scan Range	267 m (reflectivity $\geq 10\%$) 750 m (reflectivity $\geq 80\%$)
Measuring Frequency	100,000~550,000 pts/s
Scanning Speed	180~300 lines per second
Field of View	80°
Vertical Angle Resolution	0.001°
Laser Class	Class 1 Eye Safe
Number of Echoes	Unlimited waveform returns [1]
Measurement Accuracy	5mm@100m

Note: The laser sensor cannot be directly irradiated with strong laser light (including two sensors facing the light), so as to avoid high-intensity laser damage to the receiving sensor.

2.3.2 Integrated Navigation System

The airborne Position Orientation System (POS) is an inertial measurement unit (IMU) and Global Navigation Satellite System (GNSS). POS systems are used to accurately determine system velocity, position, and attitude values at specific moments in time.

1. Global Navigation Satellite System (GNSS)

Global navigation satellite system, or (GNSS) on LiAir H600 supports, mainly includes GPS, GPS (the U.S.), Galileo satellite navigation system (Europe), BeiDou Navigation Satellite System (China), and GLONASS (Russia). The GNSS of LiAir H600 includes the aviation GNSS antenna and the base station antenna.

2. Inertial Measurement Unit (IMU)

Inertia measurement unit, or IMU, consists of a high-accuracy three-axis gyroscope and a high-accuracy three-axis accelerometer. It is the benchmark center of the LiDAR system. Its role is to get the position and orientation information without external reference data.

The LiAir H600 integrates a 3-axis MEMS (Micro-Electro-Mechanical System) gyroscope, 3-axis MEMS accelerometer and dual GNSS/BD receivers into one system, the POS system. Together the POS system components gather multi-reference parameters that provide accurate, effective and reliable by optimization algorithm of integrated navigation system.

3. Inertial Navigation Accuracy

System Accuracy (post-processing)	Azimuth	0.019°(1 σ)
	Attitude	0.006°(1 σ)
Data Frequency	500 Hz	

2.3.3 Storage and Control Unit

Main functions:

1. To receive control information from ground station and accurately send the commands to the corresponding sensors.
2. To control and coordinate the normal operation of all sensors.
3. LiDAR data, inertial navigation data, photos and Log information are stored in the system's memory card.

2.3.4 Camera

This product has a built-in digital camera independently developed by GreenValley APP.

The main parameters of the built-in camera are listed below:

Sensor	APS-C
Lens	16 mm fixed-focus length lens
Effective pixels	26 MP
Pixel size	3.76 um
Image size	6252*4168
DFOV	83°

2.3.5 GNSS ground station

The GNSS ground (base) station is mainly used to observe the same point for a long time to reach a high single-point accuracy as a differential reference for the UAV mobile station. A GPS ground station is composed of a GPS antenna, a GPS receiver and a power supply.

3 Package List



① LiAir H600 LiDAR System × 1 ② GNSS antenna × 1

③ GNSS antenna assembly × 1 ④ USB cable × 1 ⑤ Card reader × 1

⑥ USB flash drive × 1 ⑦ Nonwoven fabric ⑧ Document × 1

4 Data Acquisition

4.1 Base Station Setup

1. Select an open area for positioning

Place the GNSS antenna at an open area in order to ensure the antenna can get access to the GNSS satellites as many as possible. Apart from this, the placement spot of the GNSS antenna should be stable and far away from the electromagnetic interference.

- Open areas refer to those places which are not covered by high objects. The maximum elevation mask angle of surrounding objects should be less than 15° .
- The source of strong electromagnetic interference might be cellular base station, high voltage transmission lines, or objects with high reflectance (e.g., mirror, large

water body) which may cause the multipath propagation.

2. Set up base station

Set up the base station on the selected base station point. For surveying and mapping projects or other projects with high precision requirements, a tripod should be erected in accordance with specifications, and the base station should be erected on the tripod.

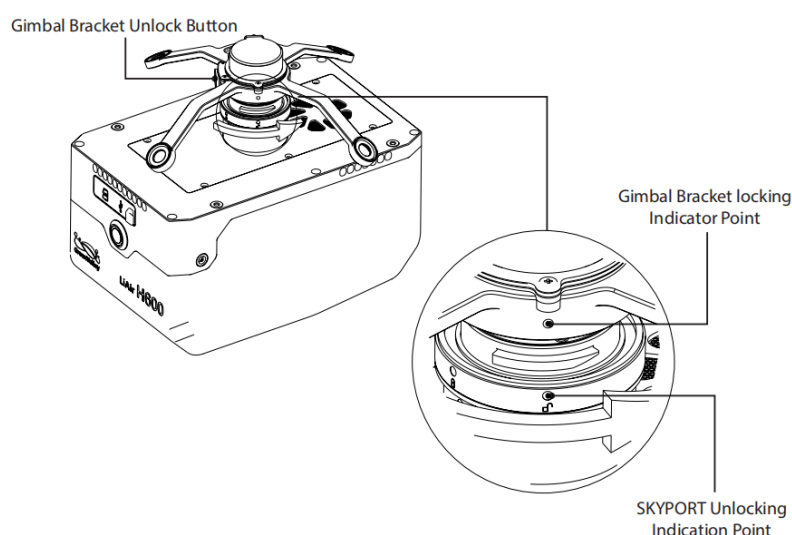
Please refer to the LiBase user manual for more specific operation process.

Note: The base station needs to start collecting data 15 minutes before the flight operation, and stop collecting data 15 minutes after the operation ends.

4.2 Equipment Installation

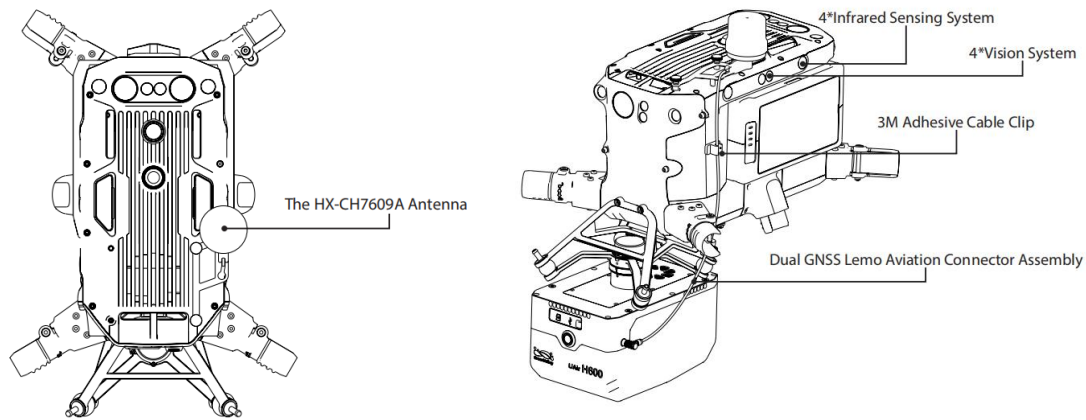
1. Mount the device onto the M300/M350 drone via the SKYPORT ring and ensure the following two conditions are normal:

- ① The Type-C interface of the SKYPORT ring is properly connected to the aircraft.
- ② The shock absorber on the aircraft mounting frame is intact and undamaged.



2. Install the GNSS antenna assembly by connecting the Lemo plug end of the GNSS antenna feeder to the port on the right side of the device (with the flight direction of the device as the front), and mount the antenna onto the bracket.

(When operating in no-antenna mode, the GNSS antenna assembly is not required.)



3. Confirm that the TF card has sufficient free space, insert it into the device, and remove the laser and camera protection covers.
4. Turn on the remote controller and power on the UAV.
5. Press and hold the ON/OFF button of the device for more than 3 seconds to turn it on.

Check the indicator status: flashing red quickly indicates the system is powered on and initializing, and solid green indicates the system initialization has been completed and the device works normally. Please refer to [Descriptions of System Indicators](#) for more specific descriptions of indicators.

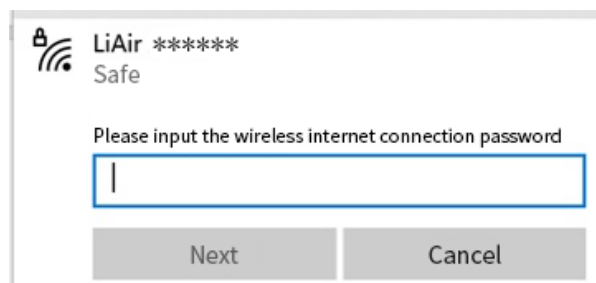
4.3 Parameter Settings

LiAir H600 will remember the parameters last set and you can skip this step if no modification is required. The LiAir H600 collection parameters mainly include laser parameters, camera parameters, and automated powerline parameters. The parameters can be modified by logging to the Web interface or using the GreenValley flight assistant.

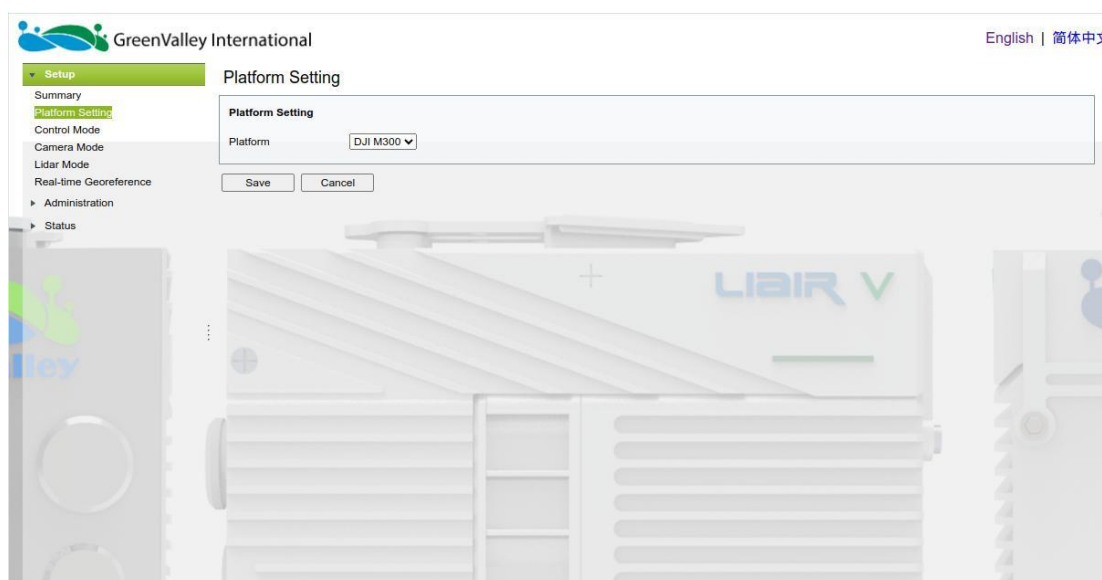
1. Setting method

(1) Login Web Page

- a) Establish the communication between the device and a computer or smart phone via WiFi network. After the device is powered on, search for the wireless network with the name LiAir_XXXXXX, click "Connect" and enter the password 66666666.




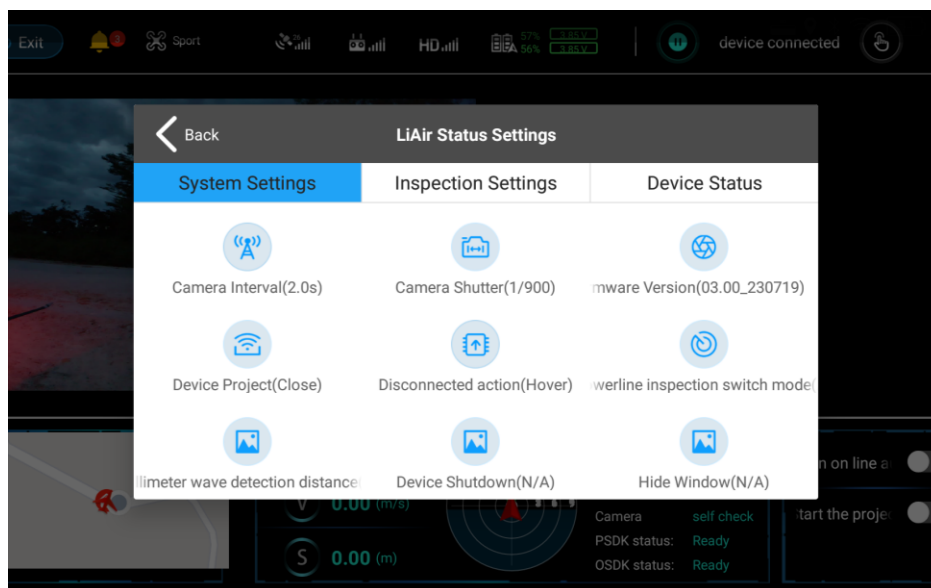
- b) Enter <http://192.168.1.88> in browser to open the LiAir H600 Web Configuration page (username: root; password: 888888). Click "System Settings" to set the device parameters.



Note: we recommend to use Google Chrome or IE11.

(2) GreenValley APP Settings

Start the GreenValley software. Click the Route Flight. The route flight interface is displayed. Click the  setting button in the upper right corner to set the equipment parameters.



2. Set parameters

This manual only describes the main parameters. For the detailed information of parameters, refer to the LiAcquire-Web manual.

a) Control modes

This section can be used to configure laser and camera data acquisition modes. LiAir H600 has the following control modes available for data acquisition:

Flight mode: This mode is the ex-factory default setting. In this mode, when the device is stationary on the ground, the device does not collect LiDAR and camera data, and automatically starts LiDAR and camera data collection after the drone takes off into the air, and automatically stops LiDAR and camera data collection when the drone is landed.

Fast Mode: Click the power (ON/OFF) button, create new project, and synchronize the collection of both IMU data and LIDAR data simultaneously.

Manual mode: In this mode, the GreenValley software's automated powerline flight interface will display a control button. You can click this button to start/stop LiDAR and camera data acquisition.

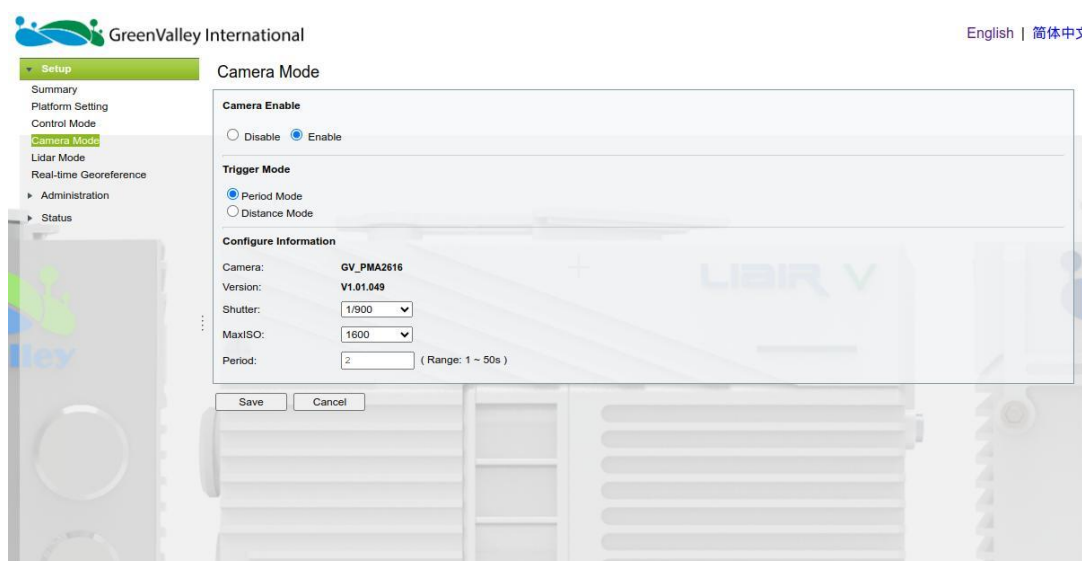
Note: the manual mode must be used with GreenValley APP, otherwise it will be impossible to activate the laser and camera data acquisition.

b) Camera modes

Camera On/Off: To enable or disable the camera.

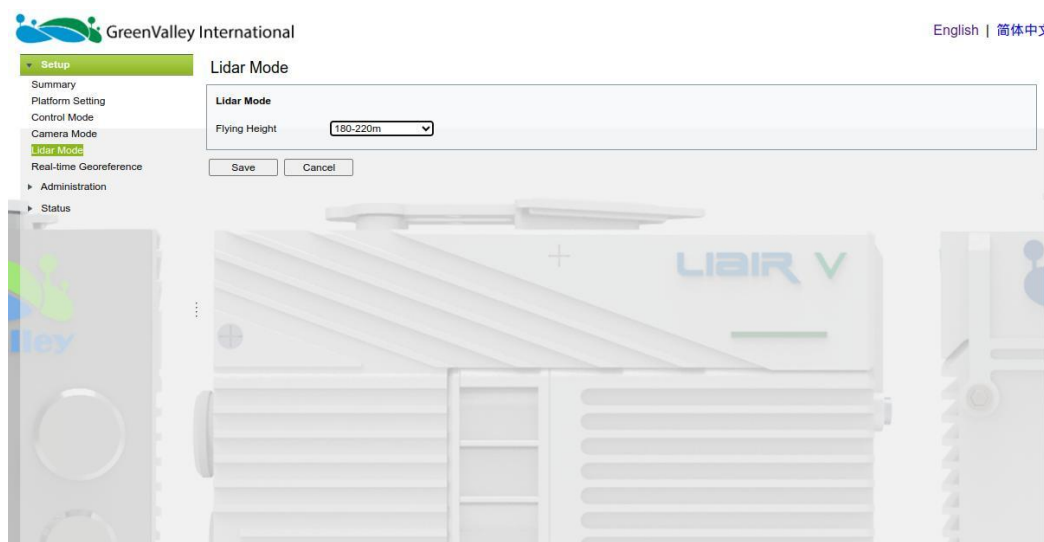
Trigger mode: Periodic mode, used to trigger the photo shooting at the preset fixed time interval (rang: 1-50s, 2s by default). Distance mode is used to trigger the photo shooting at the preset fixed interval of distance (10m by default).

Configuration: To set the interval of time or distance. This function is the same as the "Camera Interval" settings of GreenValley software.



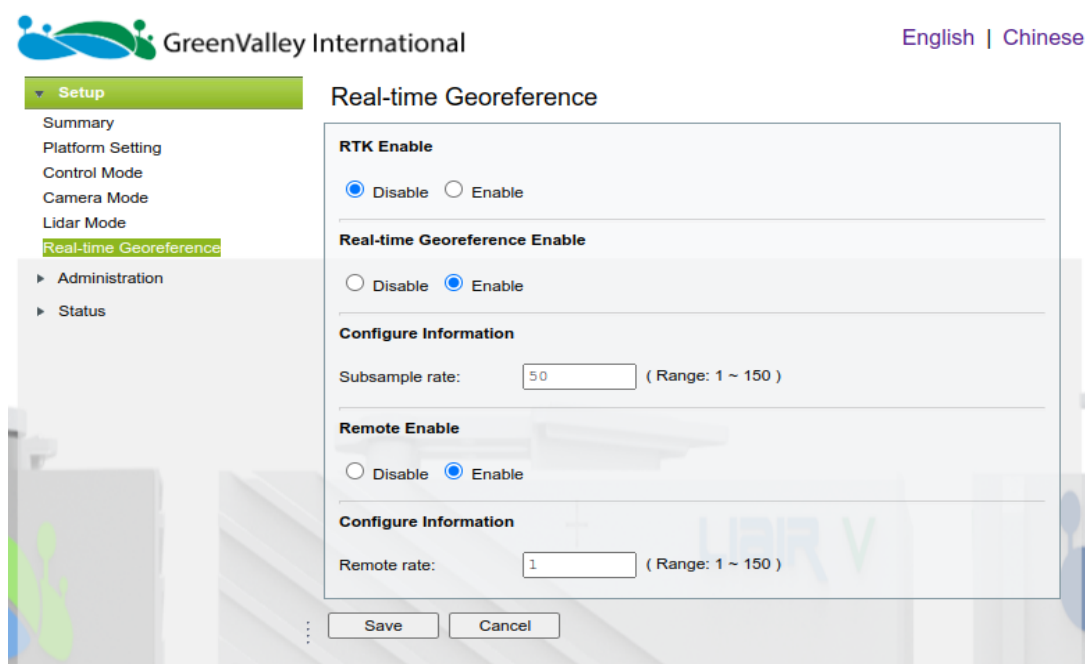
c) Flight Altitude

This section can be used to configure the flight altitude of the laser. The system will adjust the laser energy and spot frequency based on the selected flight altitude. There are a total of nine flight altitudes to choose from.



Note: The flight altitude of the web side is selected specifically in the plain area, if the height difference is large in the mountain, you need to choose a higher flight altitude according to the actual terrain relief.

d) Real-time Georeference



RTK Switch: Defaults to OFF. Used to obtain the aircraft's RTK information in real-time to improve real-time point cloud quality. When using this function, the RTK feature must be enabled on the remote controller. Otherwise, if the RTK switch is turned ON while the RTK function on the DJI remote controller remains disabled, the device's

GNSS status will show "Not Ready," indicated by a red LED.

Processing Switch: Defaults to ON. Used to enable/disable the real-time point cloud processing function. When enabled, the real-time processed point cloud will be saved in the GeoreferenceResult folder under the project directory, in *.LAZ format.

Local Thinning Ratio: The thinning factor is applied when real-time point clouds are stored in the project.

Remote Switch: Defaults to ON. Used to enable/disable the real-time point cloud transmission function. When enabled, real-time point clouds can be transmitted to the software client for live display.

Remote Thinning Ratio: The secondary thinning factor is applied to local point clouds during real-time transmission.

4.4 Data Acquisition

1. Power on the drone, press and hold the ON/OFF button of the system for at least 3 seconds to turn it on, and wait for the indicator light to be solid green, which means the system is in a normal state.
2. Log in to the Web site to set related parameters, including laser parameters, camera parameters, flight altitude, etc.
3. After the equipment indicator is normal, press the ON/OFF button for 0-2 seconds. The indicator will flash in green (1 time/second). The system creates a project and starts to record IMU data.
4. After the drone takes off, the laser and camera data automatically start to collect.
5. When the drone lands, the laser and camera data collection will be turned off automatically.
6. Press the ON/OFF button for 0~2 seconds to stop IMU data recording and shut down the project. The indicator is green.
7. Press the ON/OFF button for more than 3 seconds. The ON/OFF indicator is off and the system is powered off. Power off the drone.

5 Data Download

5.1 H600 Data Download

All data of LiAir H600 will be stored in the TF card, including project files, camera images, LiDAR data, IMU data and log files. Insert the TF card into the computer and copy the project files to the computer (folders that are not suffixed with _NAV).

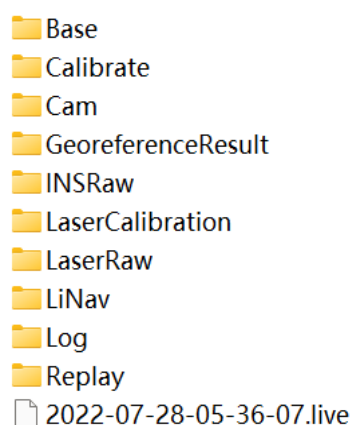
5.2 Base Station Data Download

Please refer to the LiBase user manual to download base station data.

6 Data Georeferencing

The data solution of the LiAir H600 uses the LiGeoreference software, including functions such as real-time IMU data solution, POS data solution and accuracy assessment, point cloud data solution, point cloud preliminary quality assessment, image preliminary quality assessment, three-dimensional display of point cloud data, survey, and basic analysis. For detailed functions, see the LiGeoreference User Manual. This chapter mainly introduces the process of using LiGeoreference software to solve LiAir H600 data.

6.1 Project Folder Structure



Project folder is named with UTC Time, including:

-Base folder is used to store the ground GPS base station data.

-Calibrate folder is used to store calibrated files (*.cal) and laser configuration files (*.ini). *Please notice that: do not remove or delete this folder; otherwise, the performance of georeferencing will fail.*

-Cam folder is used to store camera images and the information of exposure time, location, and attitude angles of each image (.cam).

-GeoreferenceResult folder is used to store the post-processed point cloud data calculated by the LiGeoreference software.

-INSRaw folder is used to store the raw IMU data (*.rgps,*.rimu,*.rnav).

-LaserCalibration folder is used to store the calibrated file of LiDAR (*.csv) but only available to partial series like LiAir 200 and LiAir 220.

-LaserRaw folder is used to store the raw data of laser scanner's point cloud (*.vpts).

*Note: *.vpts is the default format developed by GVI.*

-LiNav folder is used to store the intermediate file when processing the data of integrated navigation system. What's more, the final-georeferencing results of POS data are suitable to be stored as well.

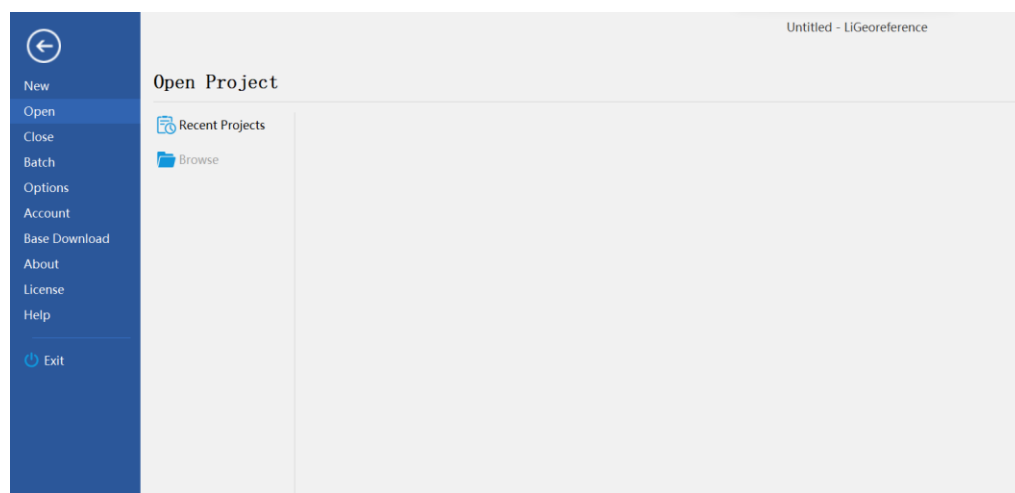
-Log folder is used to store the log information of the project showing detailed operation process.

-Replay folder is used to store the replay file of recorded trajectory and point cloud data, but only available to the specified device which supports real-time display.

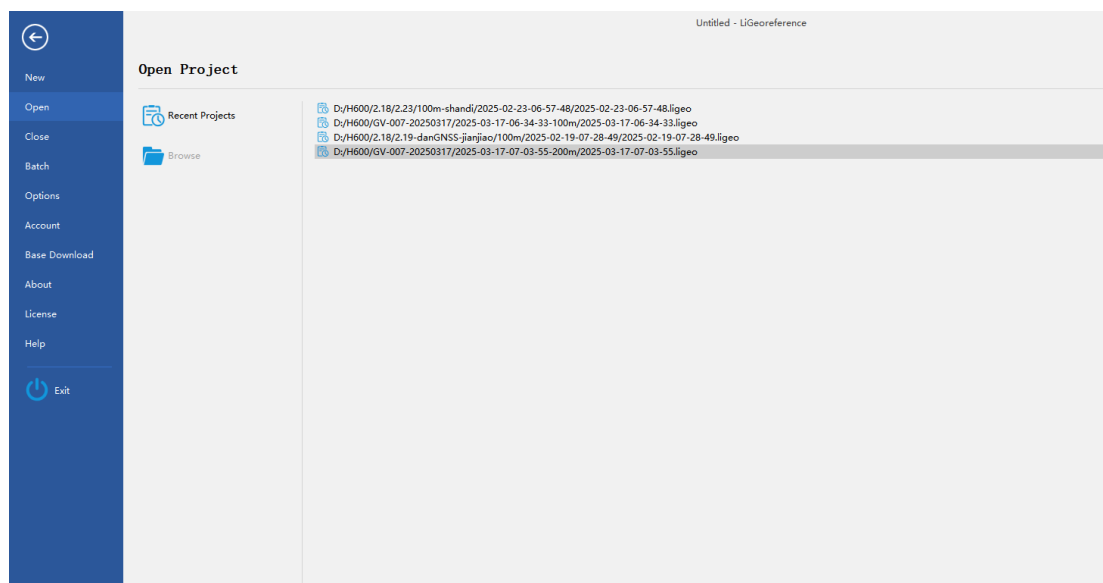
-.Live (project file) is used to record the information of project organization, configuration values, etc.

6.2 Opening Project

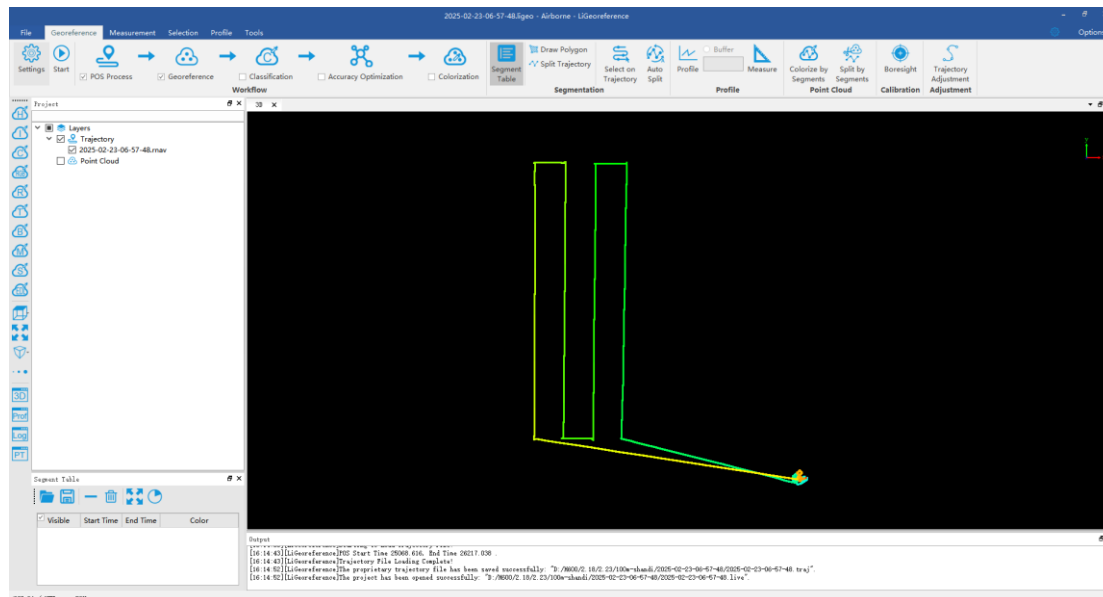
1. Open LiGeoreference software, Click "File" icon on the toolbar to open LiGeoreference project file (.live) through "Browse" icon.



- Users can also open the project file via "Recent Projects" icon which refers to history of project opened before.



- After opening the project, the georeferencing tool will automatically import the IMU file.

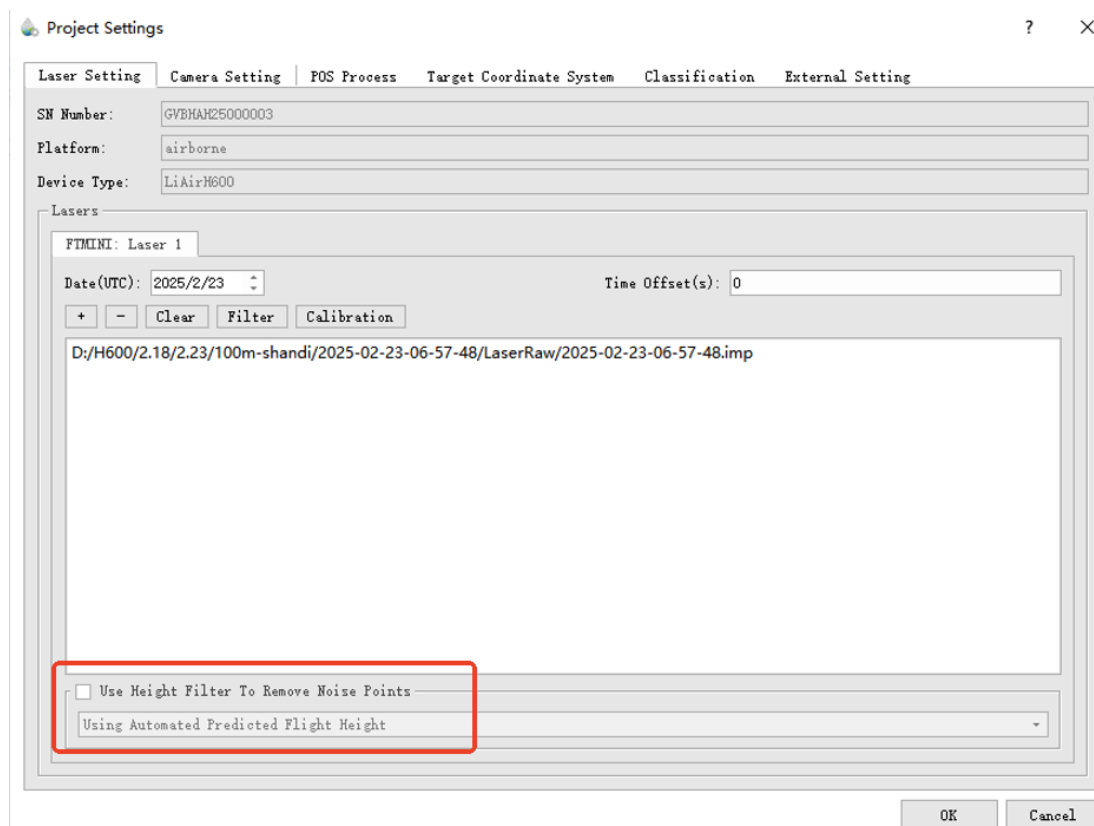
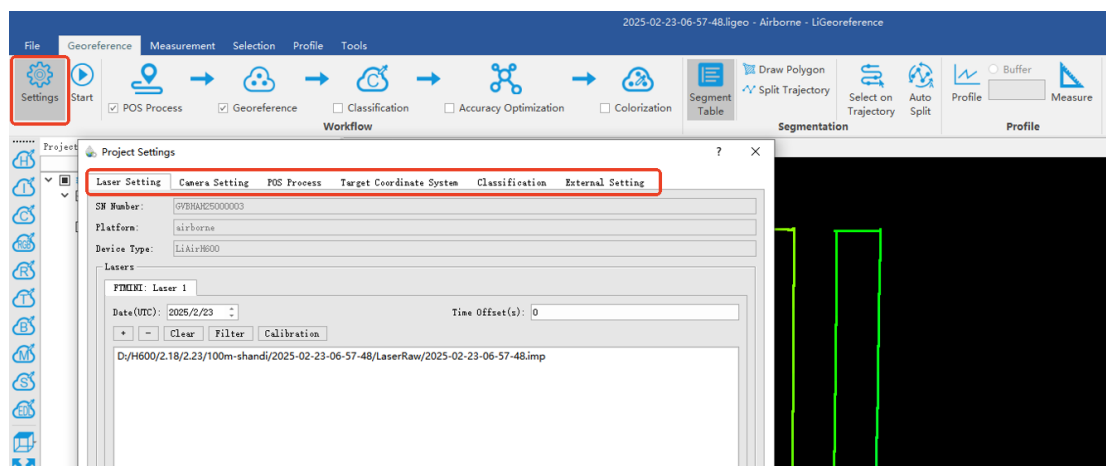


6.3 Select and Configure Parameters

Before undertaking post-processing procedure, users can use the "Settings" function to set the calculation parameters, including laser settings, camera settings, POS process, target coordinate system, classification, and smooth settings. Normally, users only need

to set POS process settings.

Height Filter Option: Located under project settings, this toggle controls elevation filtering (recommended for mountainous terrain). Default: OFF. If point cloud loss occurs after processing with this option enabled, simply disable it and reprocess the data.



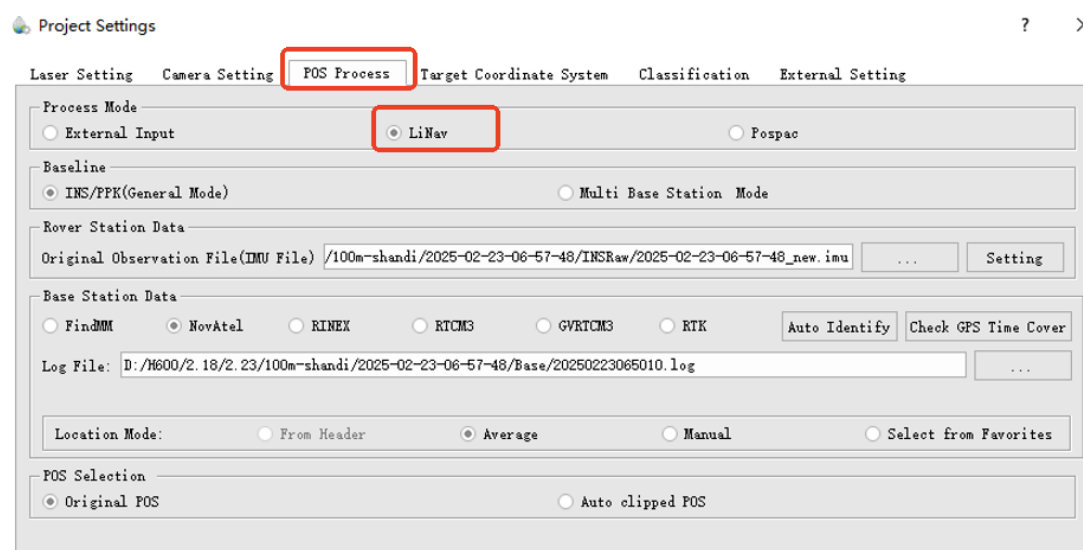
6.3.1 POS Processing Settings

LiGeoreference software has POS calculation and point cloud calculation functions. Users could directly use LiGeoreference software to calculate LiAir H600's trajectory, or choose to use other third-party software to perform POS processing procedures.

1. Use LiGeoreference to Perform POS Processing.

Click the "POS Process" button in the setting interface.

- (1) Select the LiNav processing mode.



- (2) Select the processing mode according to the length of the trajectory. It is recommended to use the general mode. When the length of the trajectory is more than 10 km, the long baseline mode can be selected.

- (3) Load rover station data, under normal circumstances, the software will automatically read the rover station data under the project folder.

- (4) Select base station data.

Under normal circumstances, the software will automatically read the base station data in the project folder, or manually load the base station data.

If the format of the local base station is the Rinex format, select the Rinex option to

load the base station data.

The screenshot shows the 'Base Station Data' dialog box. At the top, there are radio buttons for 'FindMM', 'NovAtel', 'RINEX', 'RTCM3', 'GVRTCM3', and 'RTK'. The 'RINEX' button is selected and highlighted with a red rectangle. To the right of these buttons is a 'Check GPS Time Cover' button. Below the radio buttons are four text input fields: 'Base(OBS):', 'Base(NAV):', 'Base(GNAV)-Optional:', and 'Base(CNAV)-Optional:'. Each field has a corresponding button with three dots ('...'). At the bottom, there is a 'Location Mode:' section with radio buttons for 'From Header', 'Average', 'Manual', and 'Select from Favorites'. The 'From Header' button is selected.

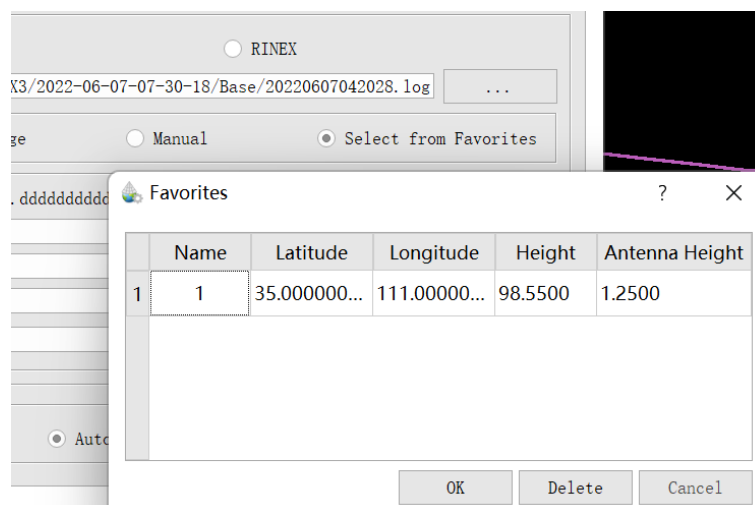
If the local base station format is Log, select NovAtel.

The screenshot shows the 'Base Station Data' dialog box. At the top, there are radio buttons for 'FindMM', 'NovAtel', 'RINEX', 'RTCM3', 'GVRTCM3', and 'RTK'. The 'NovAtel' button is selected and highlighted with a red rectangle. To the right of these buttons is a 'Check GPS Time Cover' button. Below the radio buttons is a 'Log File:' label followed by a text input field containing the path 'G:/FT800/10.27/2023-10-27-08-47-30/Base/20231027080331.log'. To the right of this field is a button with three dots ('...'). At the bottom, there is a 'Location Mode:' section with radio buttons for 'From Header', 'Average', 'Manual', and 'Select from Favorites'. The 'Average' button is selected.

(5) Enter the Base Station Coordinates.

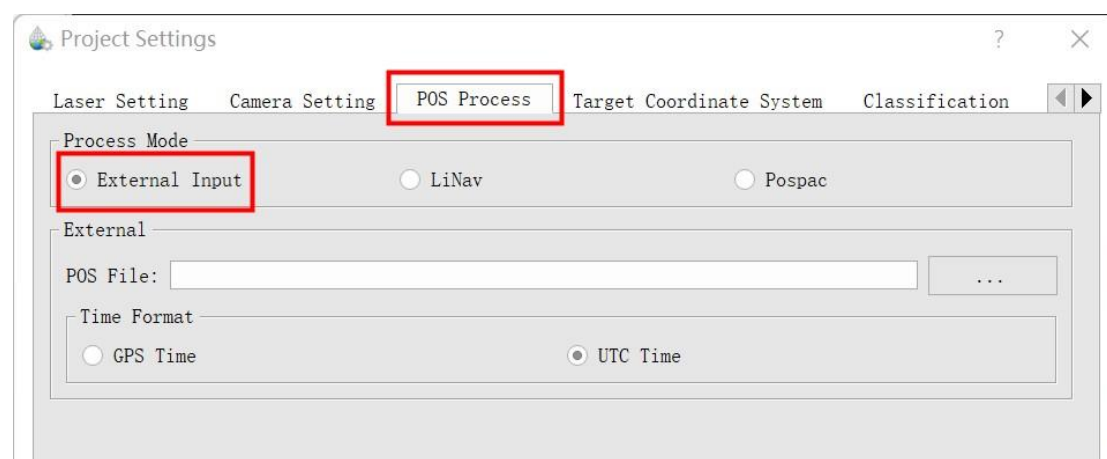
- When there is no precise base station coordinate, users could select "Average" mode. And the positioning principle is single point positioning, which leads to meter-level errors between the point cloud coordinates calculated by this method and the true coordinates.
- When there are accurate base station coordinates, users could manually input the base station coordinates. Additionally, users could use "Save to Favorites" function to save the entered base station coordinates, and later can directly use the saved base station coordinates through "Select from Favorites".
- Analyze from the data header: some base station files and base station coordinates are stored in the header file. "From Header" option needs to be clicked when users want to use this function. For example, Cloud Trajectory base station is normally stored in this mode.
- Select from favorites: Users could select the base station coordinates stored in the

software.



2. Import External IMU or Existing POS Data

Select "External Input" under Process Mode to import pos data. See the figure below.



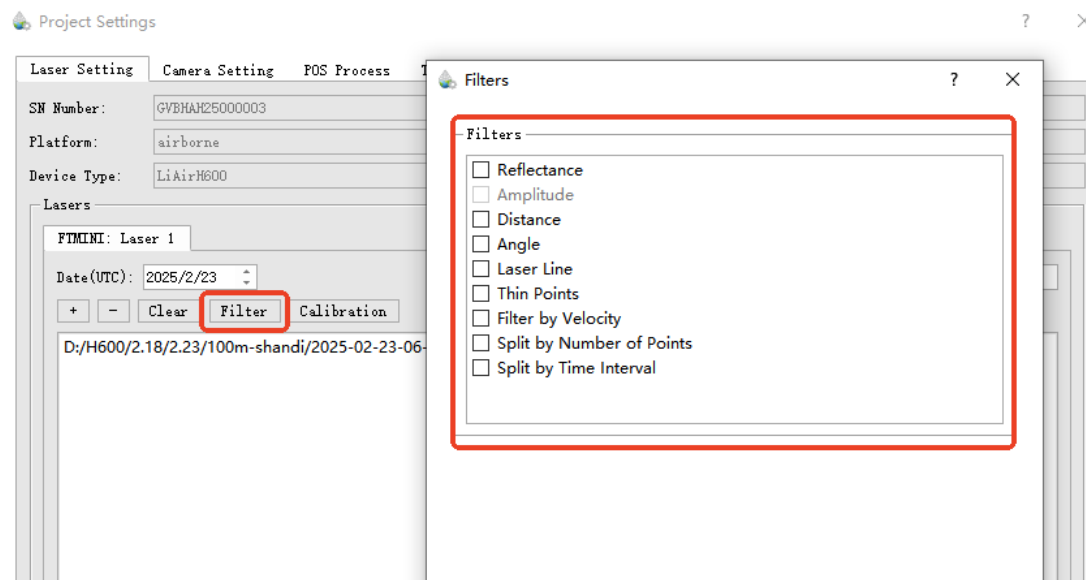
The external input function supports importing the original IMU data and the processed POS data, and the specific format includes *.pos, *.out, *.pof, *.sbtc, *.imu. See the figure below.

POS Files(*.pos;*.out;*.pof;*.sbtc;*.imu)
 POS Files(*.pos;*.out;*.pof;*.sbtc;*.imu)
 Text Files(*.txt)

6.3.2 Laser Scanner Settings

Normally, the user does not need to change the parameters of the laser setting interface.

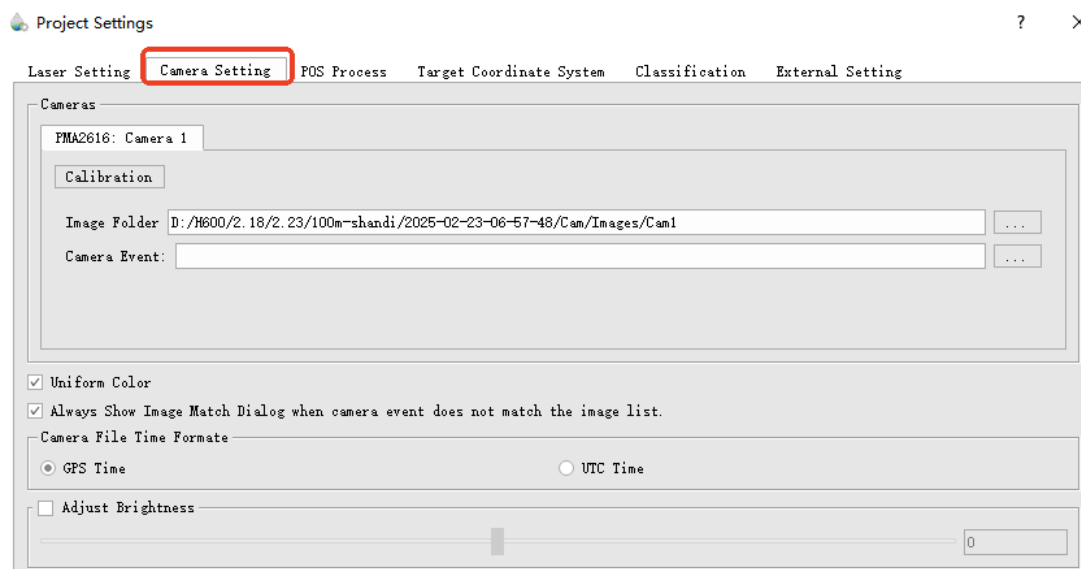
If users want to limit the output power range by reflectivity, distance and scanning angle, users could change the range by clicking "Filter" to set the parameters. For more details, please visit LiGeoreference users guide.



6.3.3 Camera Settings

Normally, users do not need to change the parameters of the camera setting interface.

Uniform Color Function: sometimes the shooting is affected by the light and the uniform color function will make the light and dark more uniform, but will blur the color slightly.

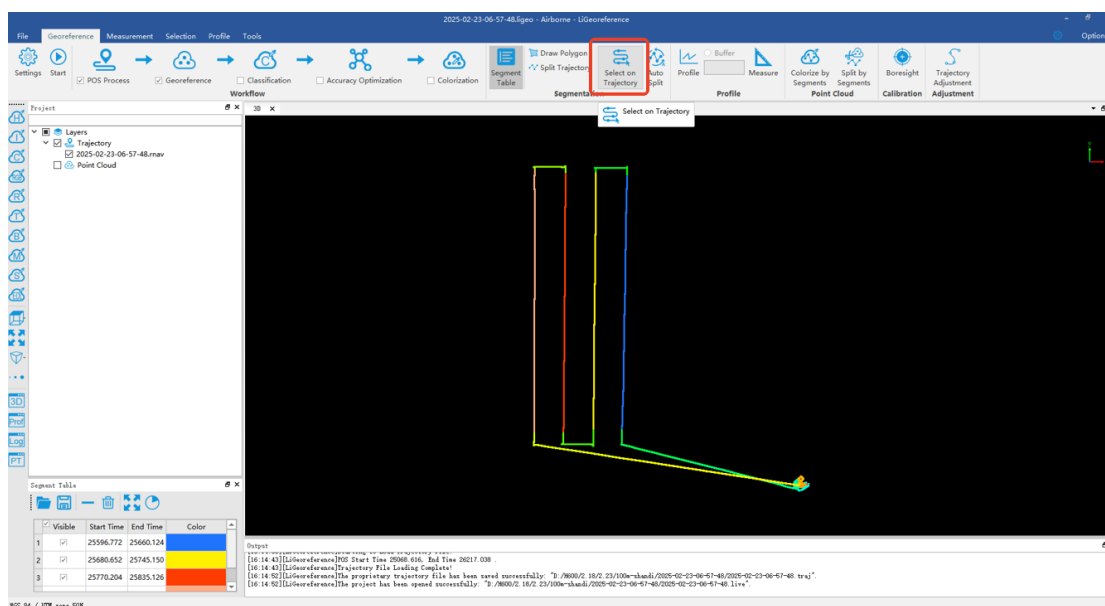


6.4 Georeferencing Point Cloud Data

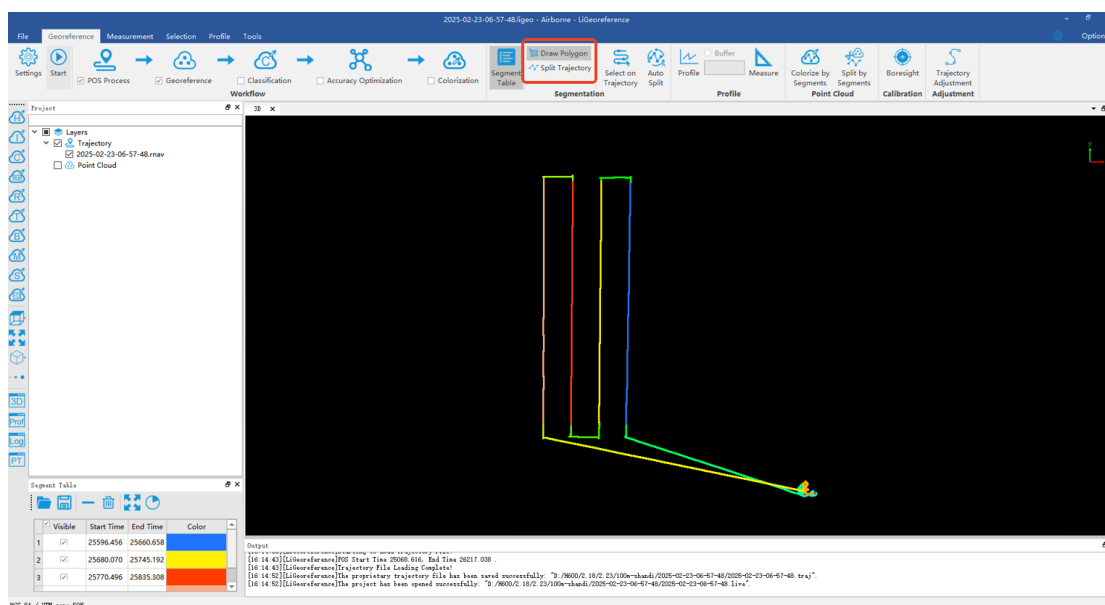
1. Select Georeference Range

Users could select the range to be georeferenced as needed. And there are two modes to be selected, including "trajectory selection" or "draw polygon". And this document only introduces the operation process of using the "trajectory selection" tool. The way of "drawing polygon" could be found in the user manual of LiGeoreference software.

(1) Click the "Select On Trajectory" button on the main interface of the software, and a table will automatically pop up at the same time, select the trajectory which needs to be georeferenced, and click OK.

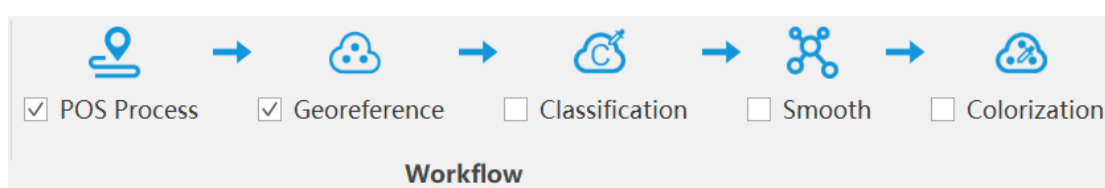


(2) If needed to select multiple trajectories, then repeat the above operation, and the selected trajectory segments will be displayed in the cutting table at the lower left corner.



2. Select processing module

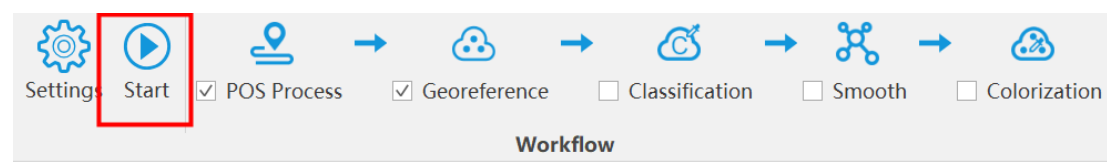
After opening the project, LiGeoreference will select "POS Process" and "Georeference" modules by default. Users could check and re-choose the function modules as needed.



Note: If there is no image data, please do not choose "Colorization" module, otherwise the program will prompt an error.

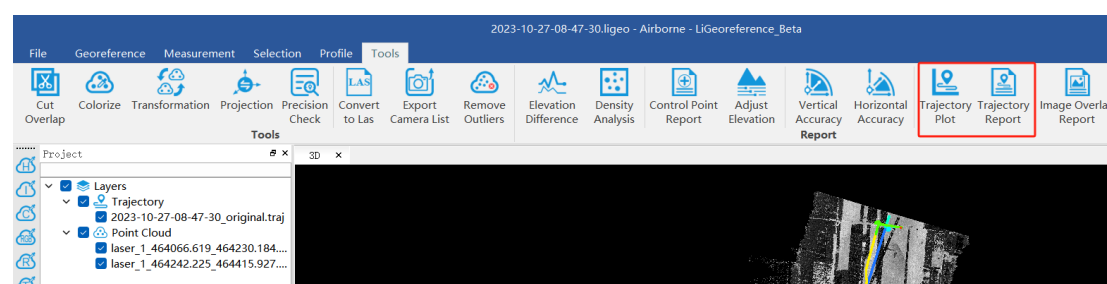
3. Data Georeferencing

Click "Start" button to start data calculation. After the calculation is completed, the point cloud is automatically displayed in the main window.



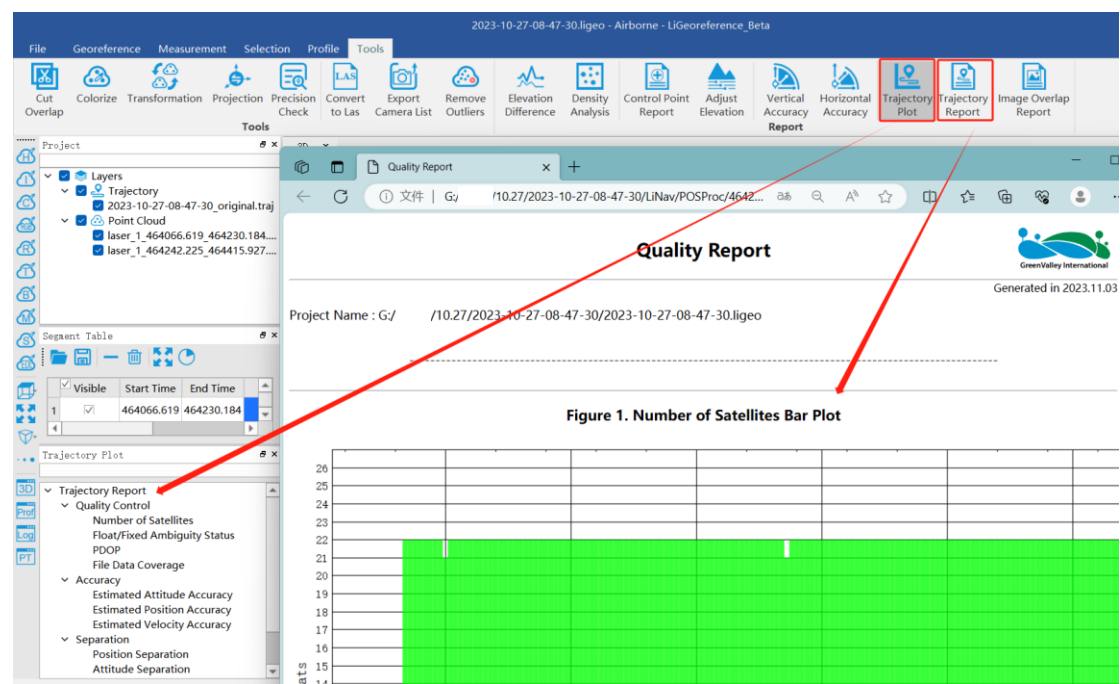
4. Data Quality Assessment Reports

If the user needs to view the "Trajectory Report" and the "Image Overlap Report", click the "Trajectory Plot" (or "Trajectory Report") or "Image Overlap Report" (only suitable for devices with cameras) under the "Tools" bar.

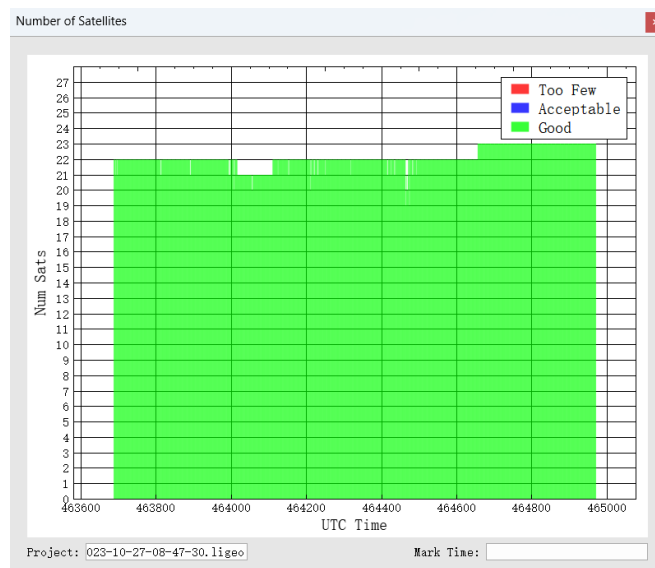


a) POS Track Report

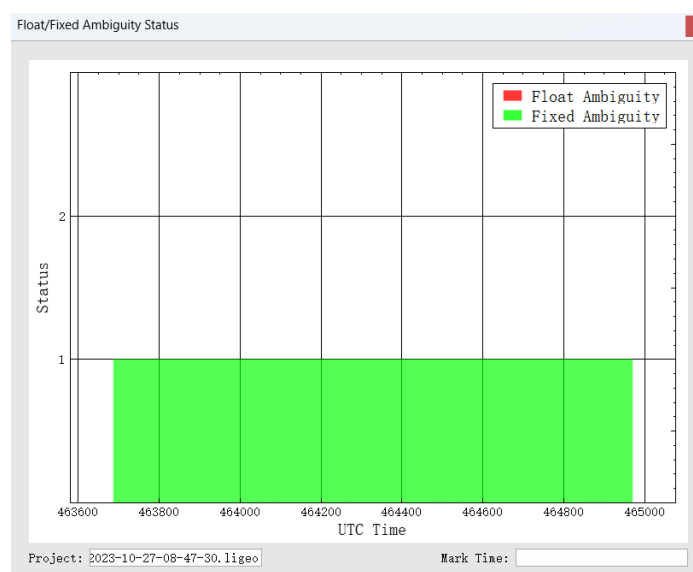
There are 11 POS accuracy evaluation criteria included in the software. Usually, the number of satellites, data coverage, estimated attitude accuracy, estimated position accuracy and PDOP value are mainly checked during data quality inspection. Users can click the evaluation index of a certain plot, or directly click "Trajectory Report" to generate a complete track accuracy report.



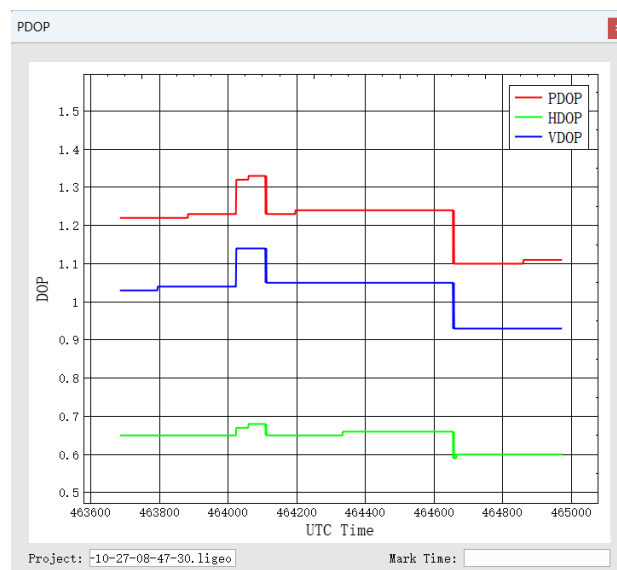
Satellites Number: Click to open the plot to show the relation between number of satellites, which can be reached, and the GPS time. This tool is used to show the number of satellites can be reached by the device each time during the data acquisition. Satellite number is shown on the Y-axis. The green part on the plot means the number of satellites is good at that time. The blue part on the plot means the number of satellites is just acceptable at that time. While the red part means the satellite number is too few to meet the requirement. The insufficient GNSS signal will result in poor data quality. If the number of satellites can be reached by the device is too few during a period of data acquisition, user can select the time period and right-click on that. Then click "Go to Time" button to find out the corresponding period on the trajectory.



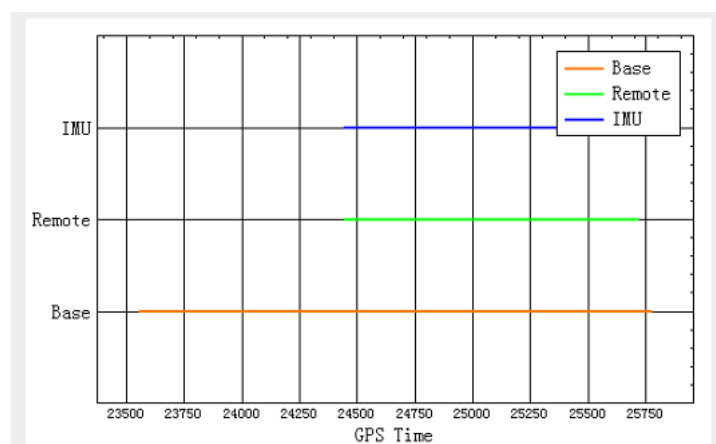
Floating/Fixed ambiguity status: Click to show the plot of ambiguity resolution status. This is used to show the situation of cycle ambiguity resolution. If the status is shown as green on the plot, it means the cycle ambiguity resolution is fixed. If it is red on the plot, it means the cycle ambiguity resolution is floating.



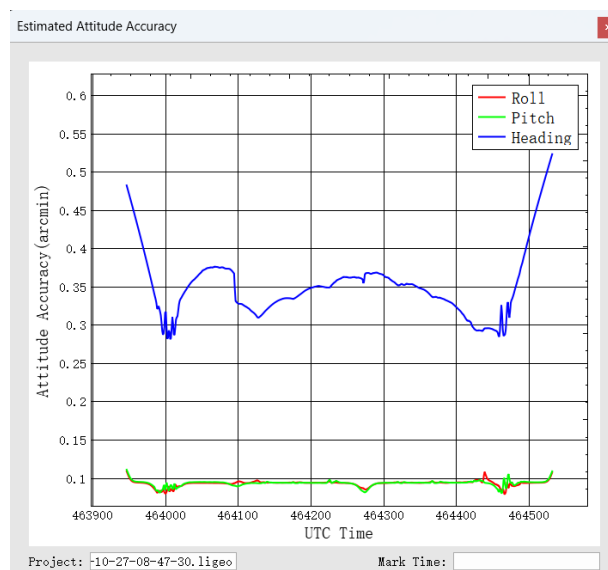
PDOP: Position dilution of precision, or PDOP, shows the distribution of the GNSS satellites. Click to show the plot of PDOP. The smaller PDOP is, the better the distribution is.



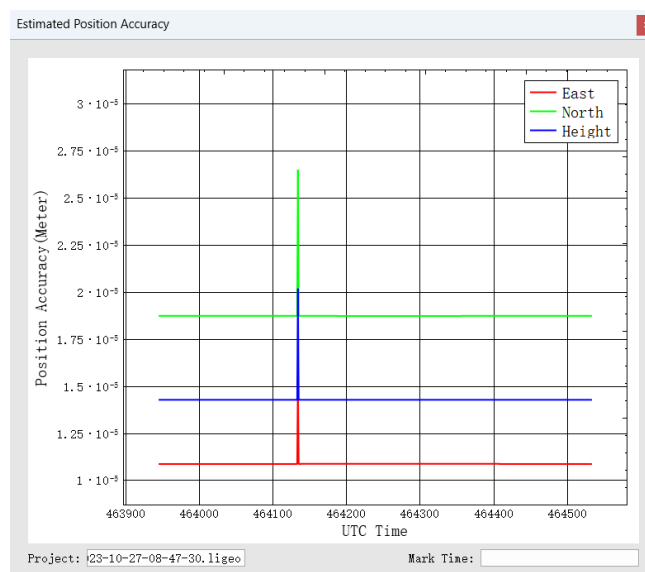
File Data Coverage: Click to show the plot of data coverage situation. This is used to show the data coverage relation among base station data, IMU data, and GNSS data of the moving device.



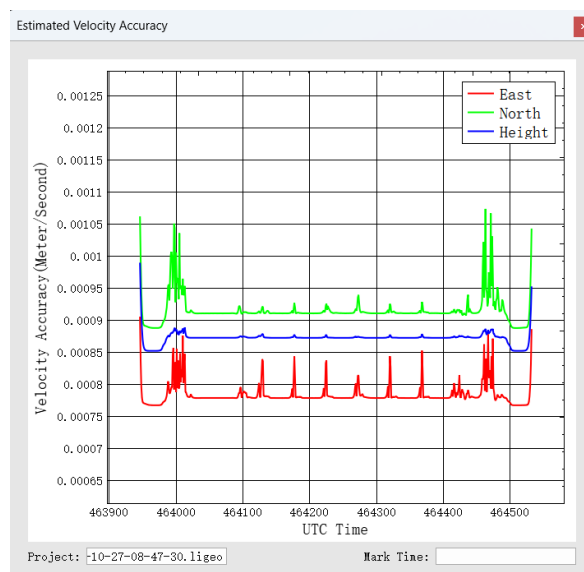
Estimated Attitude Accuracy: Click to show the plot of attitude accuracy. This plot is used to show that if the accuracy exceeds the limitation of the IMU accuracy. The X-axis shows the GPS time. The Y-axis shows the attitude accuracy. Red line is for changes in Roll direction. Green line shows the changes in Pitch direction. While the blue line shows the changes in the heading direction.



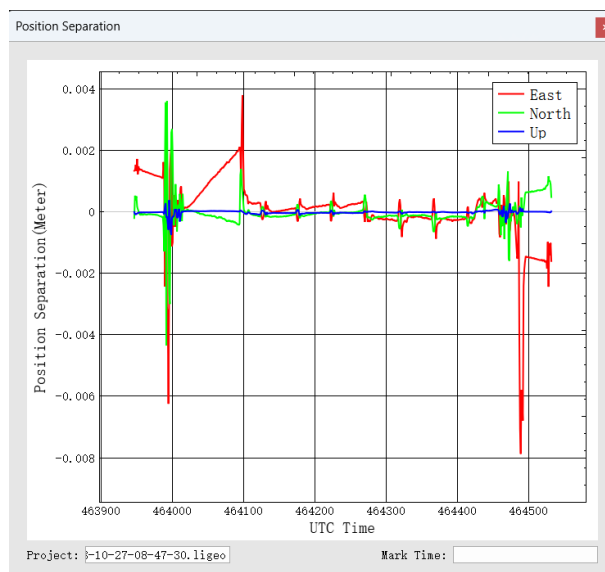
Estimated Position Accuracy: Click to plot the position accuracy. The X-axis shows the GPS time. The Y-axis shows the position accuracy. Red line is for position accuracy in East direction. Green line shows the position accuracy in North direction. While the blue line shows the position accuracy in height direction.



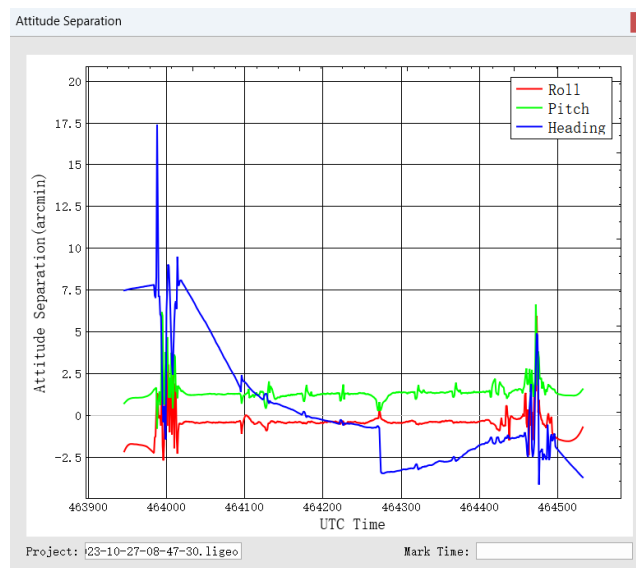
Estimated Velocity Accuracy: Click to plot the velocity accuracy. The X-axis shows the GPS time. The Y-axis shows the velocity accuracy. Red line is for velocity accuracy in East direction. Green line shows the velocity accuracy in North direction. While the blue line shows the position velocity in height direction.



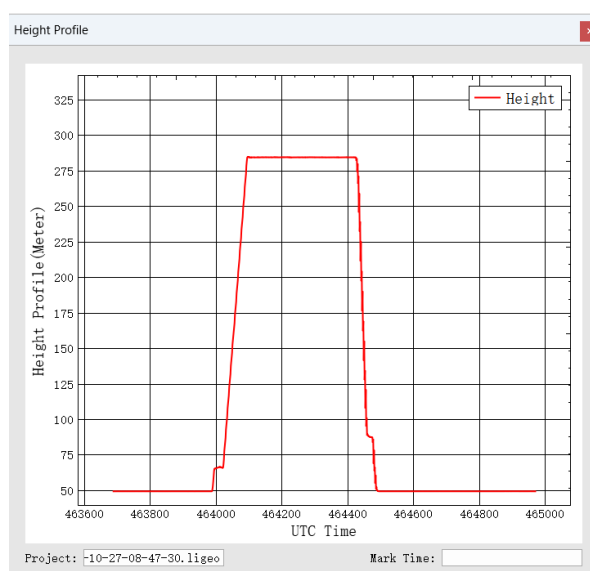
Position Separation: Click to plot the position separation. This plot shows the differences in position in East, North, and Up directions during the forward-backward processing.



Attitude Separation: Click to show the plot of attitude separation. This plot is used to show the difference among the angles in Roll, Heading, and Pitch directions during the forward-backward processing. The smaller the value is, the better the matching degree of the forward-backward processing is.



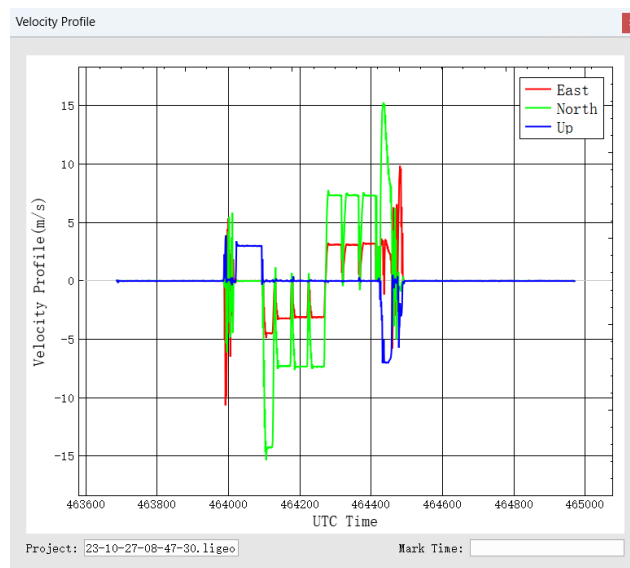
Height Profile: This plot shows the changes in height during the data acquisition.



Velocity Profile: This plot shows the changes in velocity during the data acquisition.

Red line is for the changes in East direction. Green shows the changes in North direction.

While the blue line shows the changes in up direction to the ground.



b) Image overlap report (for equipment containing cameras)

The image report lists a graph of image overlap. You can check whether there is the film drop.

CamReport ? X

☐ PointCloud

Select	File Name
<input checked="" type="checkbox"/>	laser_1_370625.765_370676.590_color.LiData
<input checked="" type="checkbox"/>	laser_1_370685.000_370732.860_color.LiData
<input checked="" type="checkbox"/>	laser_1_370741.415_370789.840_color.LiData
<input checked="" type="checkbox"/>	laser_1_370808.315_370857.015_color.LiData
<input checked="" type="checkbox"/>	laser_1_370865.615_370913.770_color.LiData
<input checked="" type="checkbox"/>	laser_1_370922.125_370970.130_color.LiData
<input checked="" type="checkbox"/>	laser_1_370978.680_371006.500_color.LiData

☒ Height

80 Meter

OK Cancel

7 System Transportation and Maintenance

7.1 Operation Notice

To ensure the reliable use of the system and the safety of the operation personnel, please observe the following notices during installation, use and maintenance.

1. Pay attention to the protection of the scanning lens to prevent scratches.
2. Handle with care during installation to prevent the system from falling or being impacted.
3. Before scanning, please make sure the scanning lens is clean and dust-free.
4. Avoid sudden changes in temperature to prevent damage to the system.
5. During the operation, it is forbidden to directly contact the laser scanning lens with any part of the body.
6. If the system needs to be transported, it must be stored within appropriate packages.
7. The operating temperature of the system is $-20^{\circ}\text{C}\sim 50^{\circ}\text{C}$. In case of rain, snow, fog, sand and other bad weather, the operation should be stopped. It can prevent equipment damage and on the other hand, it can ensure the measurement accuracy. In case of sudden bad weather during work, please move the device to a safe place in time.
8. When removing the Power cord and GNSS antenna feeder cable, hold the both ends of the connector. The removal should be gentle and appropriate.
9. Non-professionals, without permission, please do not try to disassemble the equipment, do not repair it without permission, so as to avoid accidents or aggravate the damage of the equipment. If the equipment is modified or disassembled not authorized by GreenValley International Inc., the warranty will be void.

7.2 Equipment Maintenance

1. Before turning on the device, check whether the scanner lens is clean, if there are any stains, it should be cleaned immediately.
2. After the equipment is used, check whether the scanning window of the scanner is dirty. If it is dirty, it should be cleaned up immediately.
3. Regular cleaning: Use special lens paper to gently wipe the laser scanning lens, and wipe from the inside to the outside in a circular manner.
4. The storage temperature range of LiAir H600 is $-20^{\circ}\text{C}\sim+60^{\circ}\text{C}$, and the storage environment requires ventilation and dryness.
5. Make sure that all power is turned off before storage, and the equipment is stored in an appropriate box.
6. If the storage time is more than one month, the power-on test should be carried out.
7. During the transportation of LiAir H600, the packing box equipped at the factory should be used.
8. If it needs to be packed separately due to special circumstances, please ensure that the packing box has a certain pressure resistance, and label the outside of the box with signs such as "**Precision Instrument**", "**Handle with Care**", "**Fragile**", etc. to avoid equipment damage.
9. The instrument is a precision instrument, avoids violent impact during transportation and handling, and avoids damage to the optical components in the instrument or causing direction deviation.
10. During the warranty period, customers can enjoy free firmware update services. After the warranty period has expired, customers can purchase firmware update services.