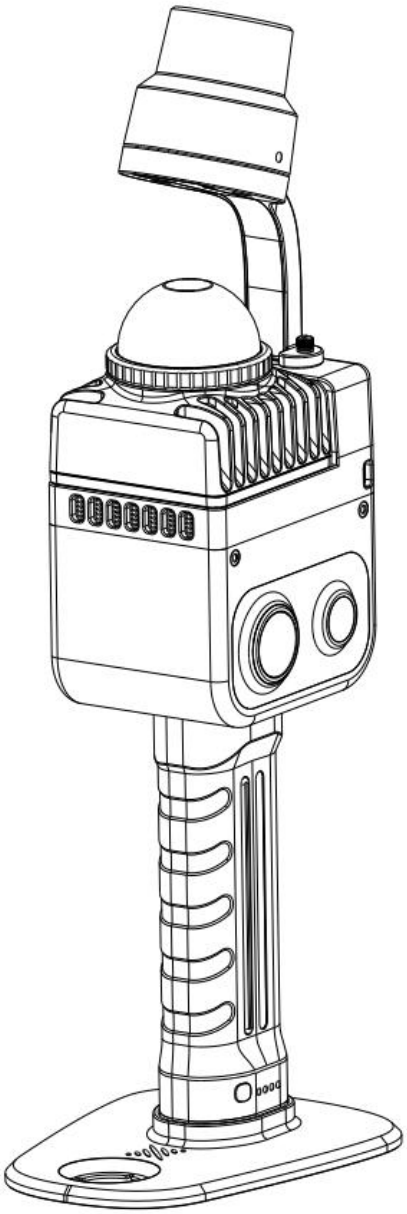
LixelKity K1 Handheld Scanner

User Manual(V2.3)

2025.8



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1 Product Overview

LixelKity K1 is a lightweight and compact handheld real-time 3D reconstruction device launched by XGRIDS. Weighing in at less than 1kg, whilst integrating 48 million pixel * 2 panoramic vision and 360° LiDAR, generating centimeter-level color models in real time. For professional, small and medium-sized customers and 3D enthusiasts, we provide convenient 3D reality capture and modeling solutions.

2 Basic operation

2.1 Battery installation

1. Press the battery buckle
2. Insert the battery into the bottom of the device and ensure it is inserted tightly.
3. Loosen the buckle and confirm that the battery is locked.

Note: Failure to lock the battery may cause the device to slip.

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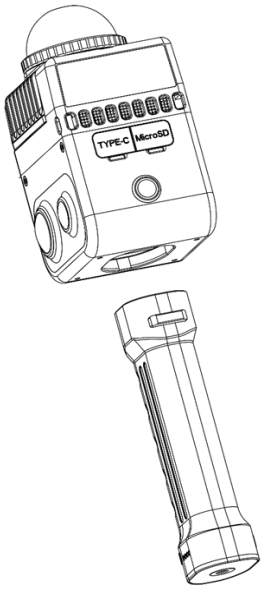
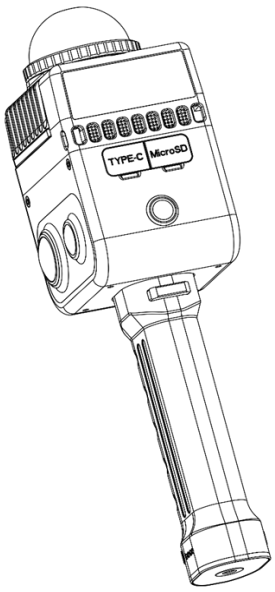
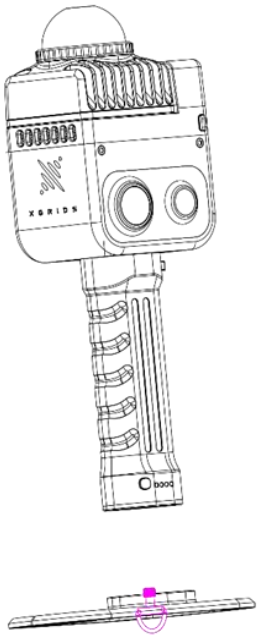
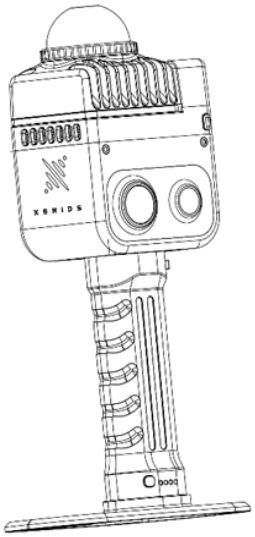




2.2 Base mounting

The battery handle has a threaded hole at the bottom, clip the device into the base, lock the bottom bolt, and place the device in a flat position.





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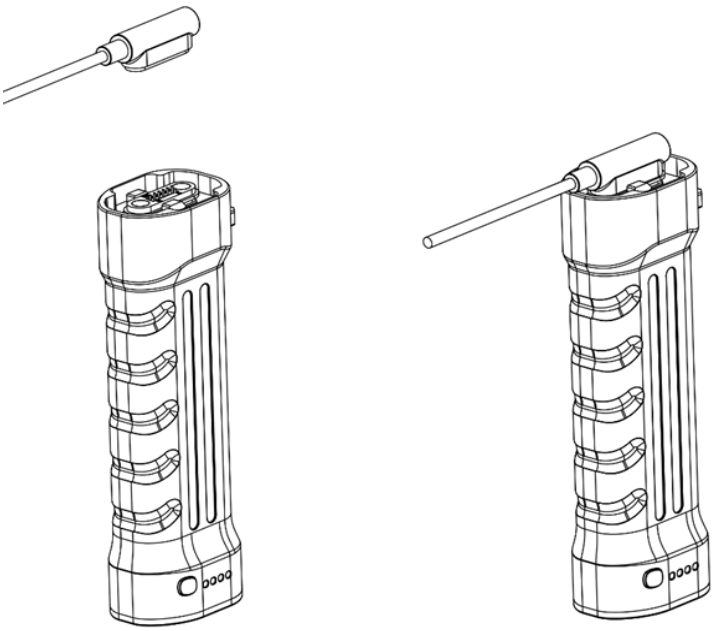
2.3 Battery charging

Use the provided charging cable, connect the charging adapter to the battery, once the indicator light starts flashing, the battery is charging.



Battery full charge time: about 2 hours. During the charging process, the indicator light indicates the current battery level. Please refer to the table below for details.

Flashing Pattern	Battery Level
	0-24%
	25%-49%
	50%-74%
	75%-99%

2.4 Function key operation

Function	Button Operation	Device Status
Power On	Press and hold for 4 seconds	The indicator light will change from slow flashing blue to solid green, indicating the device has entered standby mode.
Power Off	Press and hold	While in standby mode, long press for 4 seconds. The

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	for 4 seconds	indicator light will change from solid green to flashing white, indicating the system is saving data. The device powers off once the indicator turns off.
Start Scanning	In standby mode, double-click the button.	The indicator light will switch from solid green to fast-flashing green, then slow-flashing green. The LiDAR will begin to rotate, indicating that scanning has successfully started, and the device has entered scanning mode.
Stop Scanning	In scanning mode, double-click the button.	The indicator light will change from slow-flashing green to fast-flashing green, then solid green. The LiDAR will stop rotating, indicating that scanning has successfully stopped, and the device has returned to standby mode.
Control Point Collection	In scanning mode, single-click the button.	The indicator light will stay on for about 1 second, then return to slow-flashing green. This indicates successful control point recording.
Switch to USB Mode	In standby mode, single-click + indicator light turns white + single-click	After a single click, the indicator light will turn white and remain for up to 3 seconds. During this white light period, single-click the button again to switch to USB mode. If no further action is taken within 3 seconds, the device will remain in its original mode.

2.5 Indicator light description

Indicator Light Status	Meaning
No light	Device not started
Slow-flashing green light	Scanning mode
Solid green light	Standby mode
Solid blue light	USB mode
Solid yellow light	Device not activated
Solid red light	System error
Slow-flashing blue light (~30s)	Powering on

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Solid white light	Switching between standby and USB mode
Fast-flashing green light	Scan starting/stopping
Light alternates between red and green	Upgrading

2.6 Data Transfer Instructions

To transfer data, connect the device to a computer using the provided USB 3.1 cable while the device is in standby mode. Use the app or the power button to switch to USB mode. Once the device is recognized, you can proceed with data copying.

Notes:

The USB mode will automatically disable after a device restart.

If you want to continue scanning after enabling USB mode without powering off or disconnecting the device, you must manually exit USB mode.

Using other USB cables may result in slower transfer speeds or other issues.

A common problem could be that the USB cable could only be recognized in one direction. When rotating the Type C port 180 degrees, with the other side pointing up, it cannot be recognized by the device.

2.7 Basic usage specifications

1. The LixelKity K1 handheld scanner is a kind of precision surveying and mapping equipment. Falling or being hit by external forces may damage the equipment, leading to abnormal work or bad accuracy, or even complete damage to the equipment.

2. When using a tripod, make sure to tighten the tripod and the device cartridge battery to prevent the device from falling.

3. The protection level of the LixelKity K1 canner is IP54 . Please pay attention to the environment when using it and do not use it in an environment exceeding this protection level. It is recommended to use a soft dry cloth or a self-cleaning cloth to clean the equipment. Please keep the LiDAR module and lens parts clean and do not touch them directly with your hands.

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4. Do not cover or touch the heat dissipation part of the equipment during use. When the device temperature is too high during use, it may automatically shut down.

3 Device activation and connection

3.1 LixelGO Introduction

LixelGO is a mobile app that comes with the Lixel L and K series scanner. It can be connected and synchronized through WiFi and 5G/4G real-time transmission services, switch between true color and elevation preview modes quickly, support viewing and managing projects, and achieve management of digital 3D space assets in cloud. Scan the code to install the latest version of the app.

IOS version

Go to the App Store and search LixelGO to download and install the latest version of the app.

3.2 Recommended installation environment

Recommended phone configuration :

Module	Specs
CPU	Recommended Snapdragon series, preferably Snapdragon 8 or above
Random Access Memory	Minimum 8GB
Display chip	It is best to have an independent display chip

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Other	it needs to support Bluetooth and Hotspot function; larger storage memory preferred; and longer battery life preferred.

Recommended :

Brand	Product	Processor CPU	Random Access Memory	Graphics card GPU
VIVO	IQOO NEO 6	The first generation Snapdragon 8 + mobile platform	12GB	Adreno 730
Redmi	Redmi K50 E-sports Edition	Qualcomm Snapdragon 8 Gen 1	8GB	Adreno 730
Huawei	Huawei P50E	Snapdragon 778G	8GB	Adreno 642L
OPPO	OPPO K10	Dimensity 8000-MAX Mobile Platform	8GB	Mali-G510 MC6

3.3 Device activation

1. Register and log in to LixelGO

After installing LixelGO, open the app and click Use now to enter the login/registration interface. New users should choose to register by email or mobile phone number. Registered users can log in by account and password or mobile phone verification sms.

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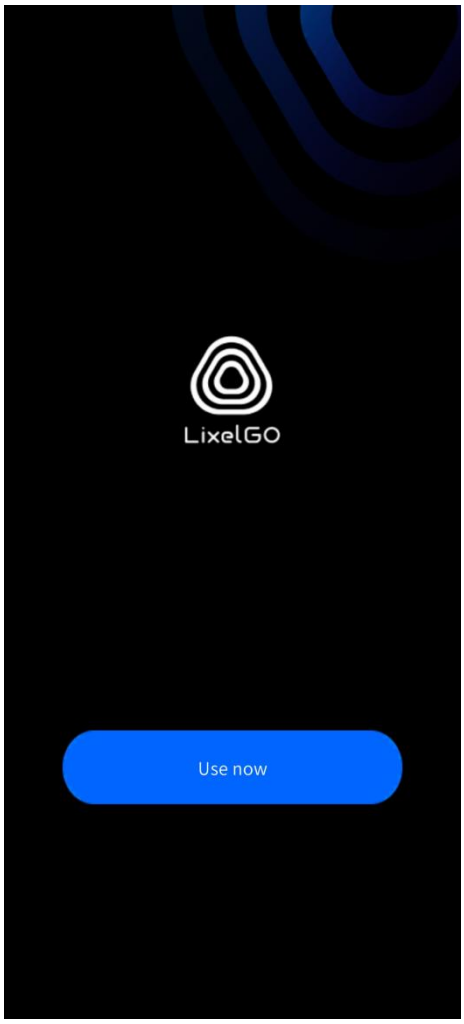

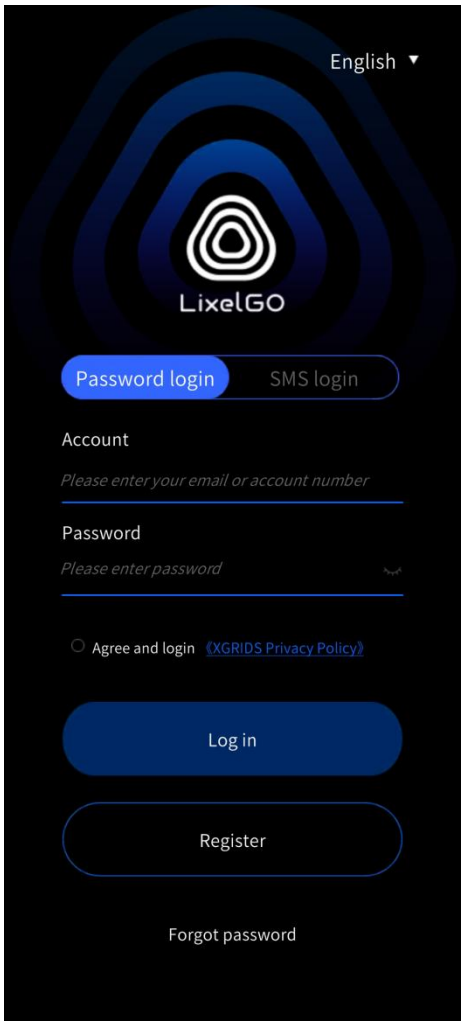

2. Forgot password

If you have registered an account but forgot your password, you can click "Forgot password" to reset it through the registered phone number or email.

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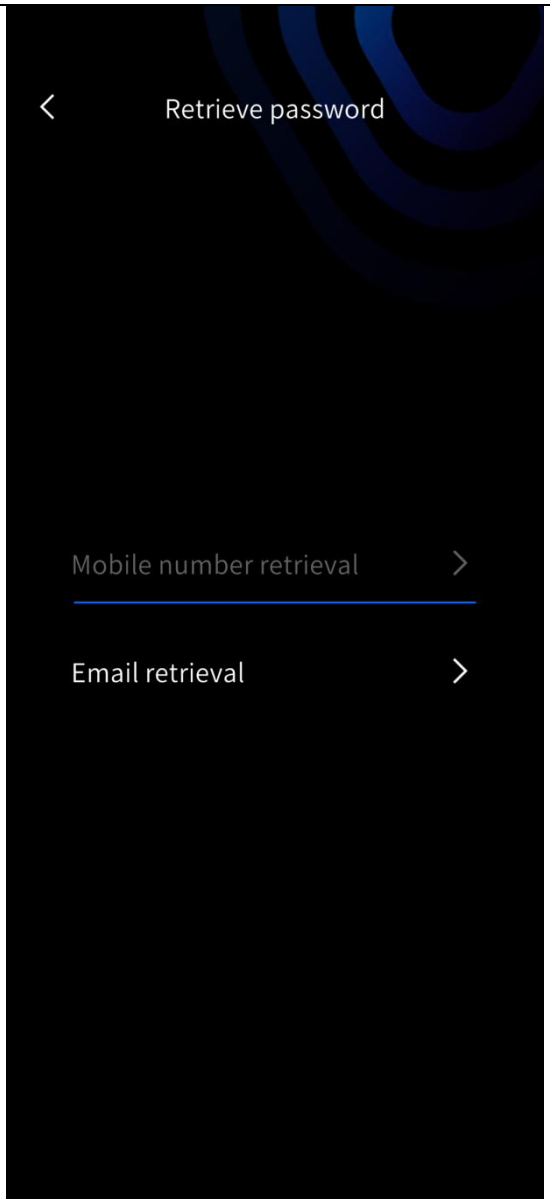

3. Switch language

By clicking on the lower right corner of the screen to setting and switch languages, currently supports Simplified Chinese and English two language modes.

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4. Add new devices

Press and hold the power button to turn on the handheld scanning device, and the indicator light will flash from blue to green for successful startup.

Direct Connect Mode: Click Add new device, enable permissions, and then follow the steps.

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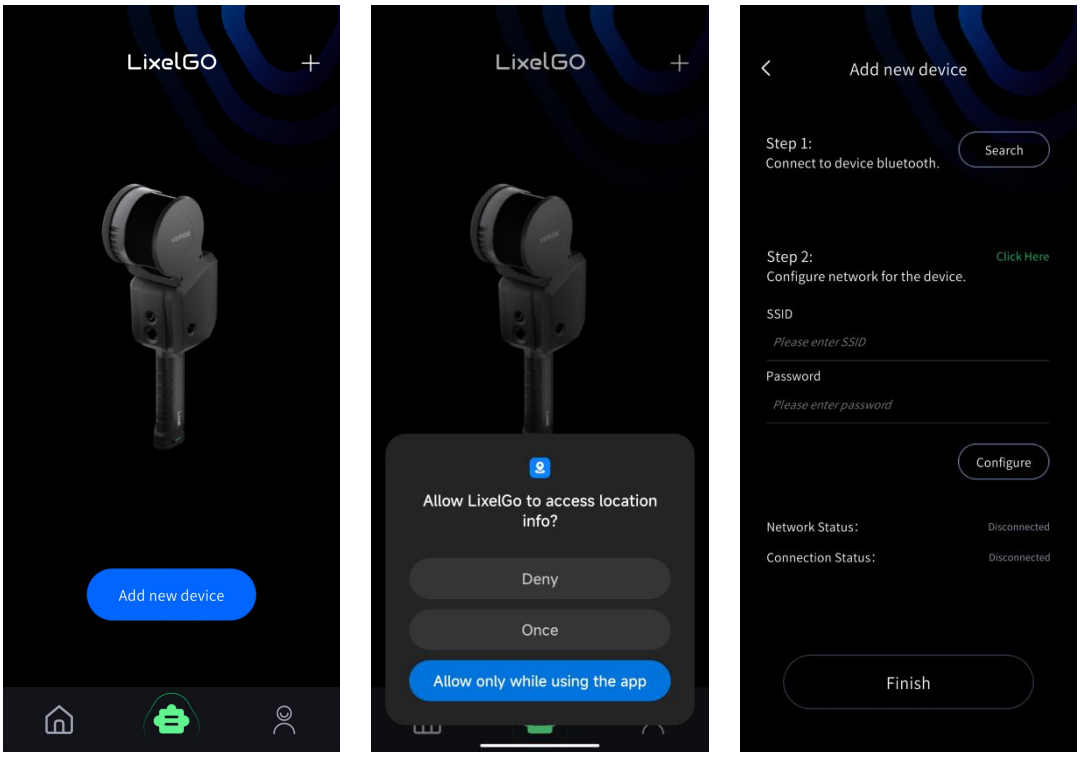
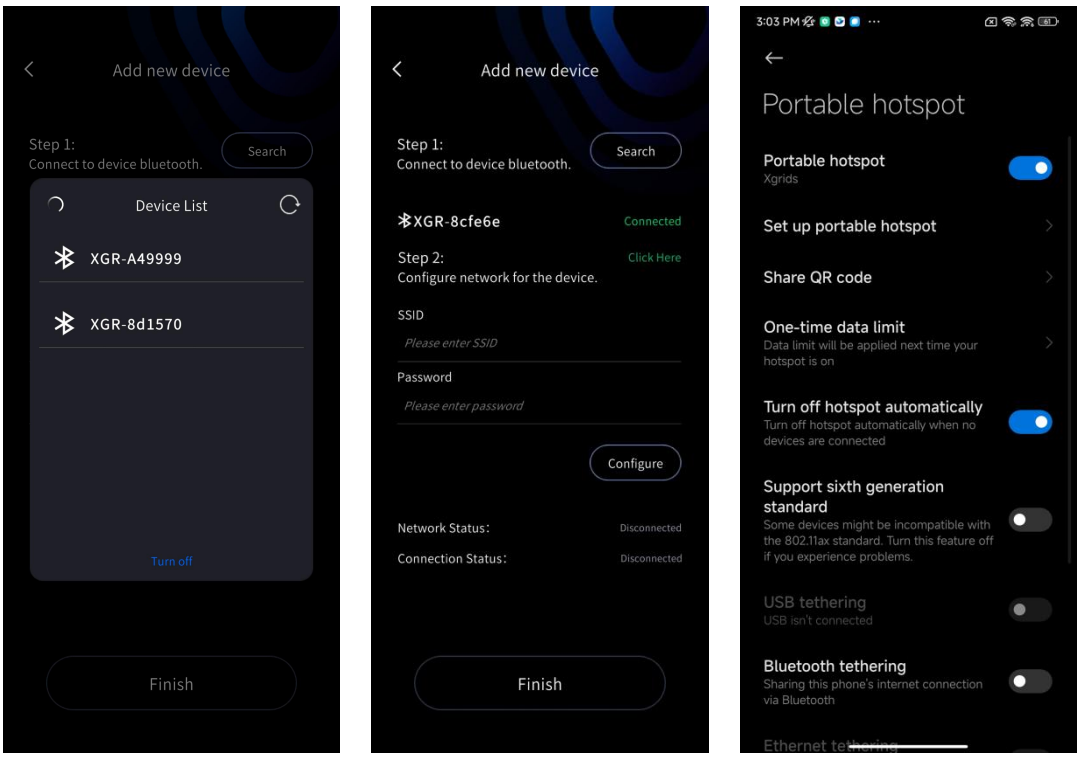


The first step is to turn on the phone's Bluetooth, search for and connect to the corresponding device's Bluetooth. The second step is to configure the network for the device. First, open the phone hotspot [set the hotspot name and password as simple as possible], enter the hotspot name and password, click on Configure, and the app will automatically connect to the phone hotspot.



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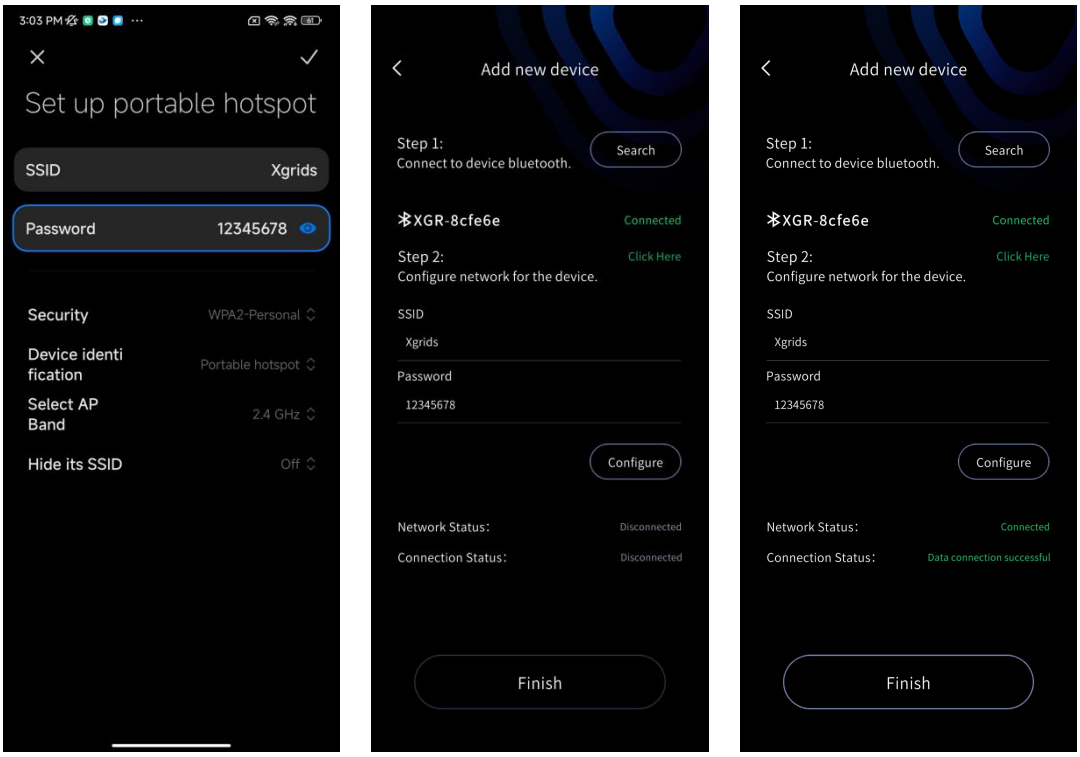

When both the network connection status and data connection status are displayed as successful, click Finish to view the basic information of the currently connected device.

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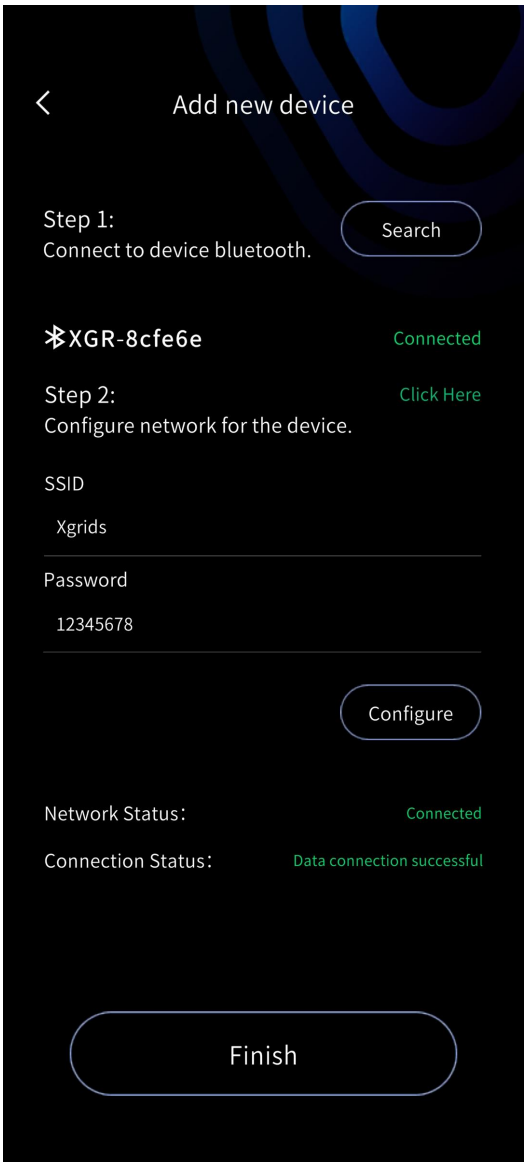

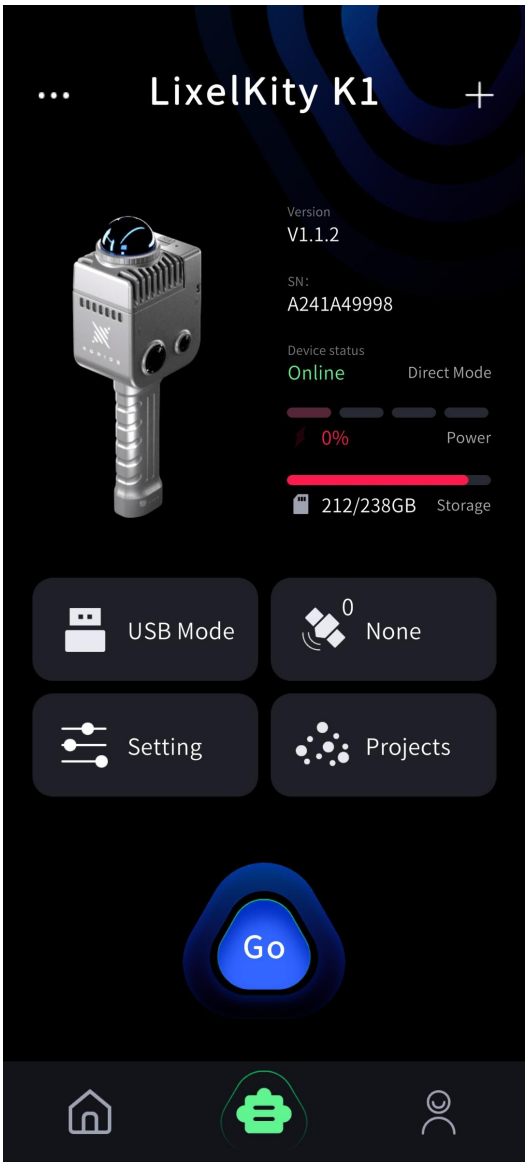

Bridge Mode : Click the plus sign in the upper right corner of the interface, select Bridge Mode, enter the interface, and then follow the operation steps.

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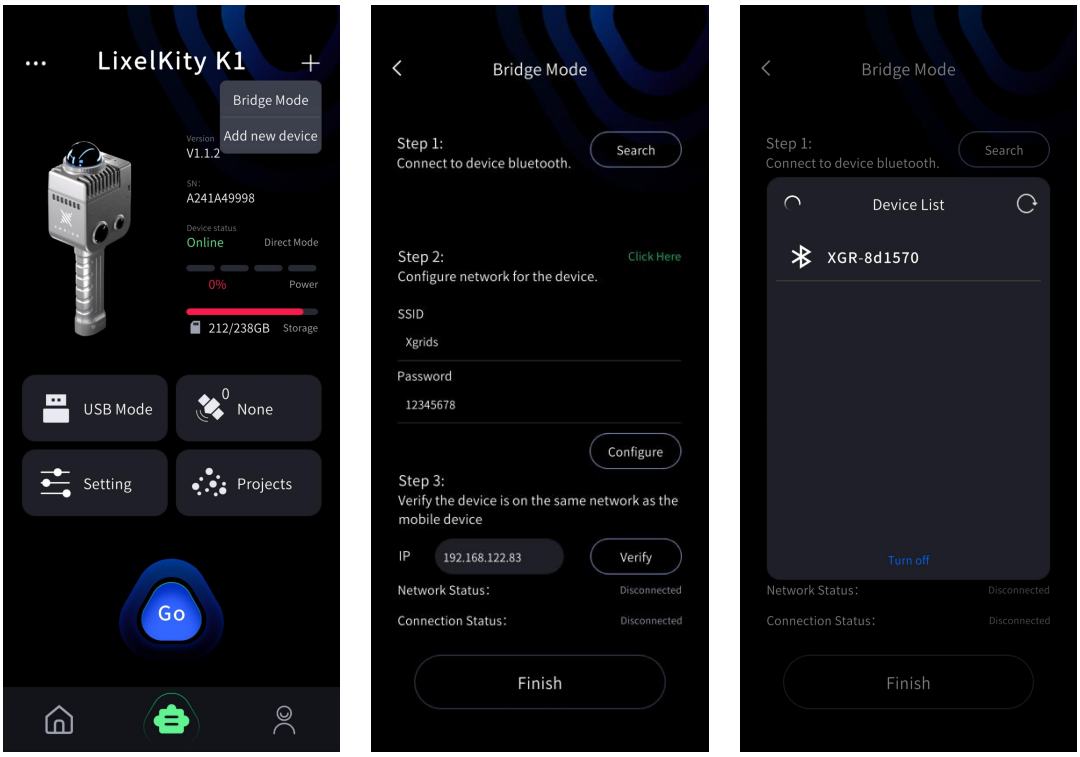
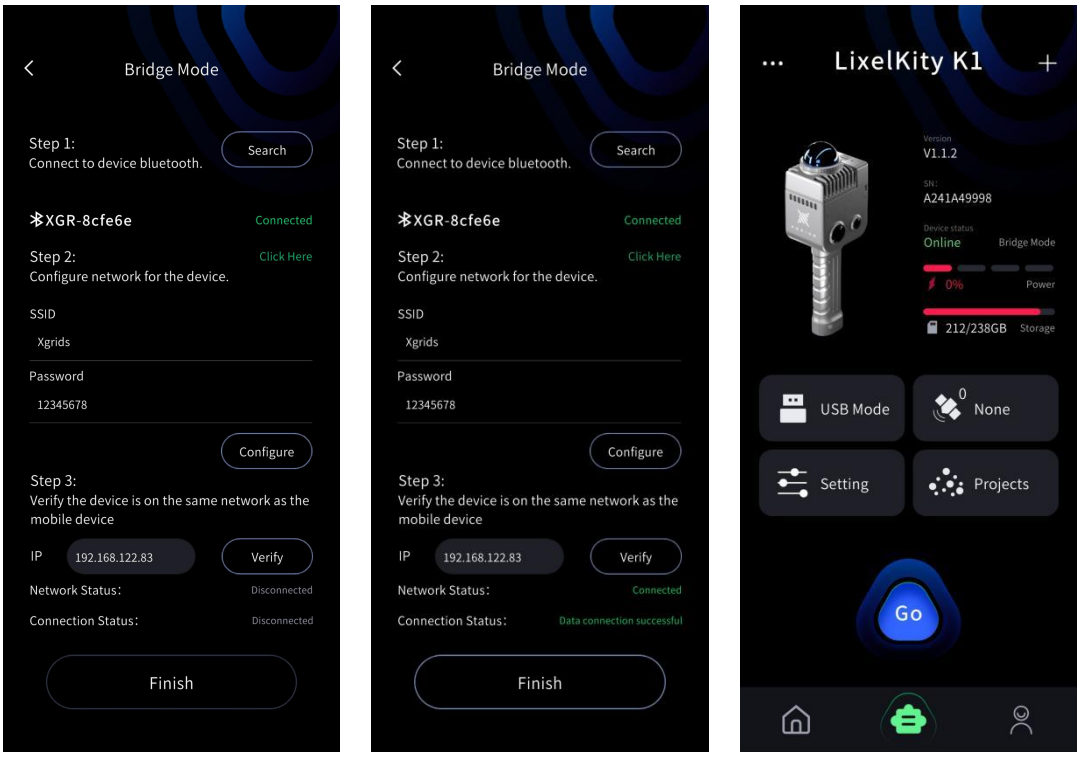


The first step is to retrieve the device's Bluetooth. The second step is to configure the network and verify it. After the correct connection, click Finish to view the device's basic information.



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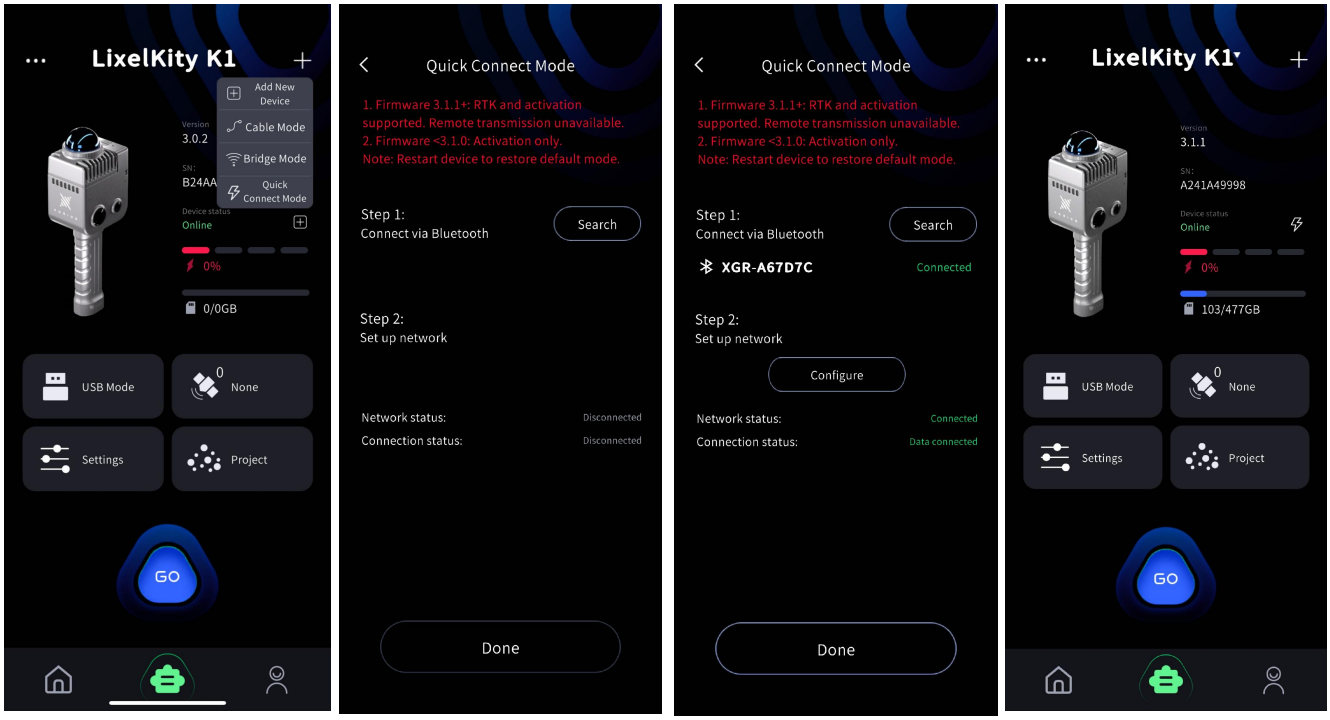
Quick Connect Mode:

Firmware 3.1.1+: RTK and activation supported. Remote transmission unavailable.

Firmware <3.1.0: Activation only.

Restart device to restore to default mode.



IOS version

Before using the app, you need to do some settings for your iPhone first. Click on "Settings" to enter "General," then go to "About." Modify the "Name" field to contain only English characters without using any spaces or special characters. This "Name" is used as the SSID for the phone.

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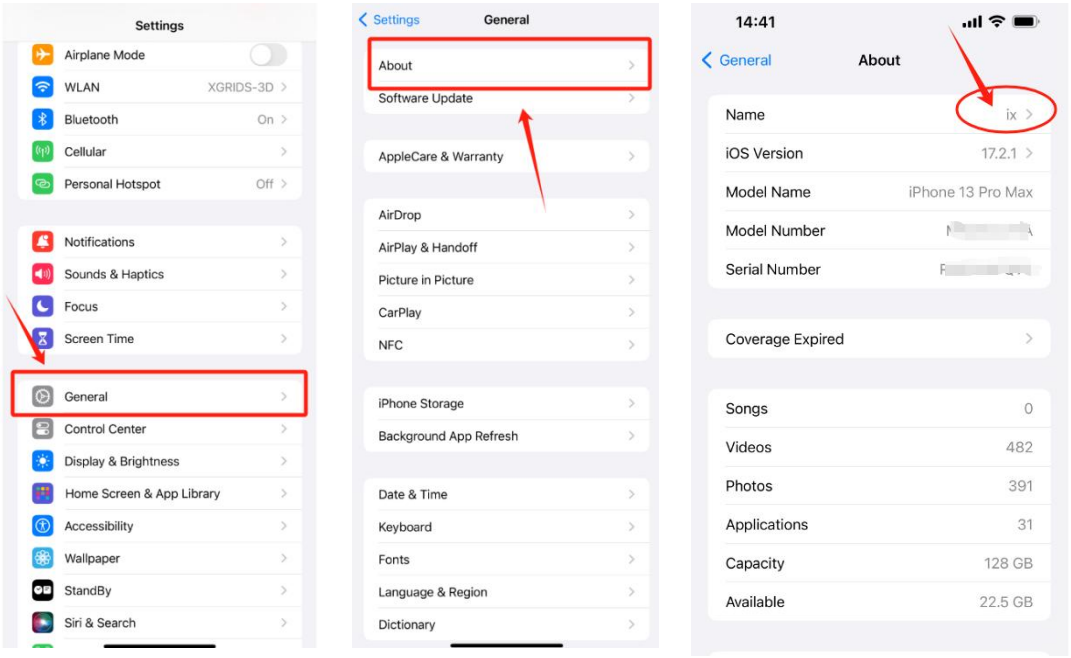
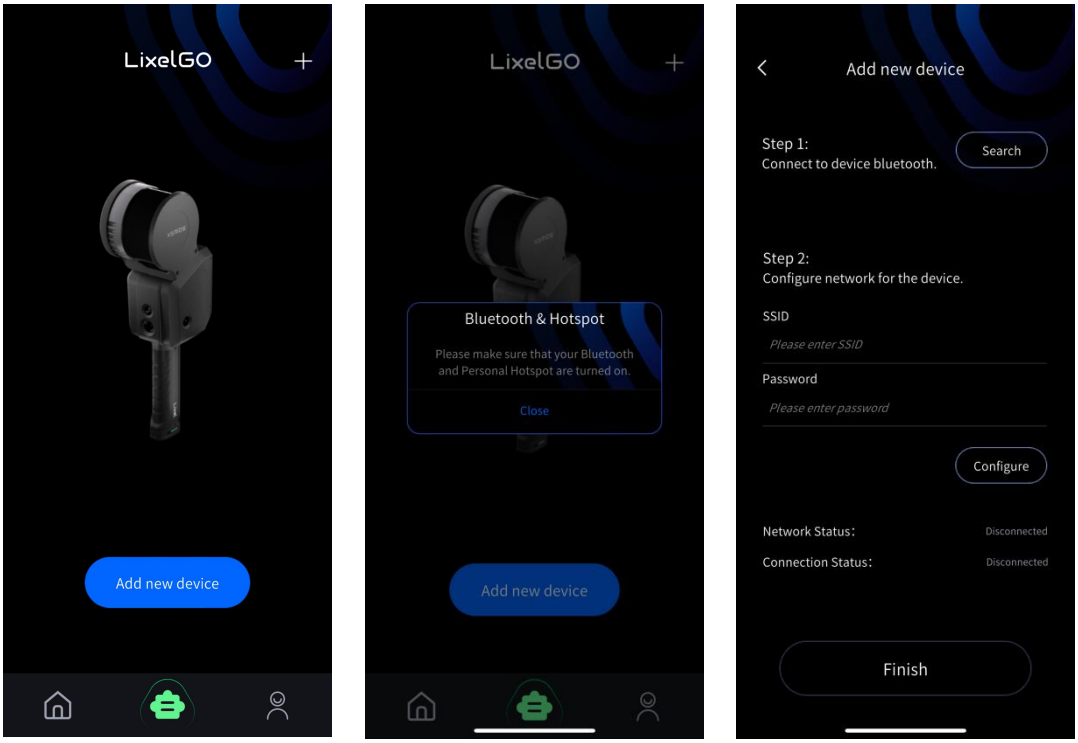


Press and hold the power button to turn on LixelKity K1, and the indicator light will flash from blue to green for successful startup.

Direct Connect Mode: Click Add new device, click close, and then follow the steps.



First Time Connection:

Permission requires clicking "Allow."

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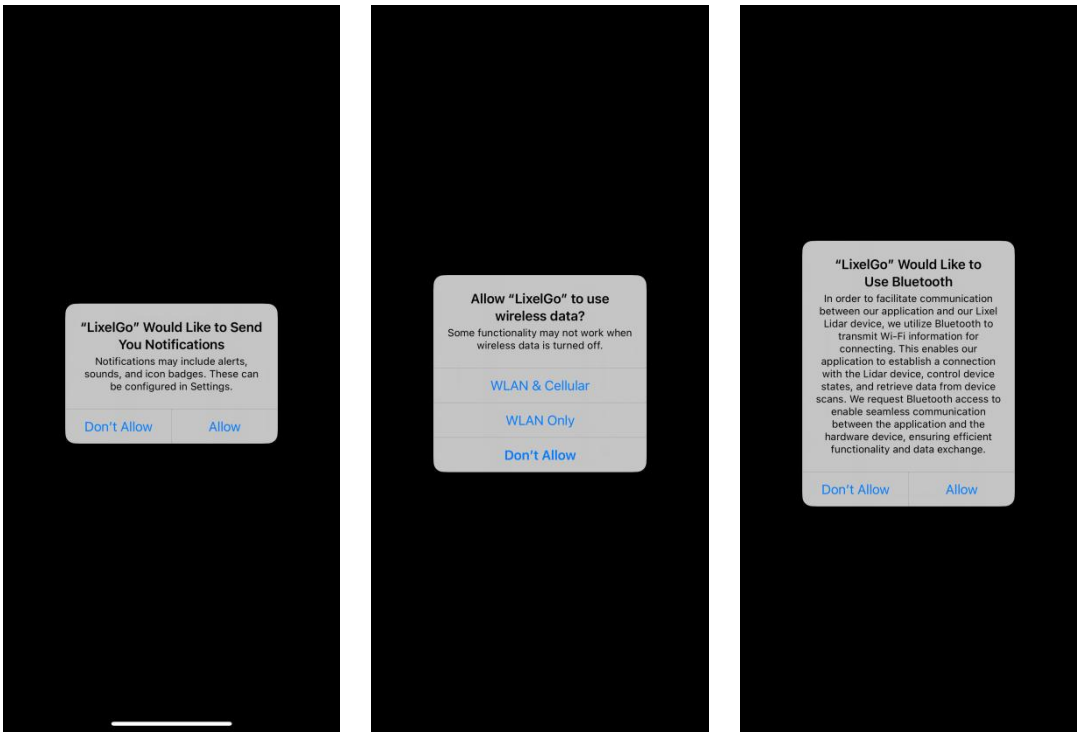
Select "WLAN & Cellular."

Permission requires clicking "Allow."



Turn on the phone's Bluetooth, search for and connect to the corresponding device's Bluetooth. The second step is to configure the network for the device. Enter the device name of your iPhone and the password of your hotspot. Set the password as simple as possible. Click on Configure, read the tips carefully.

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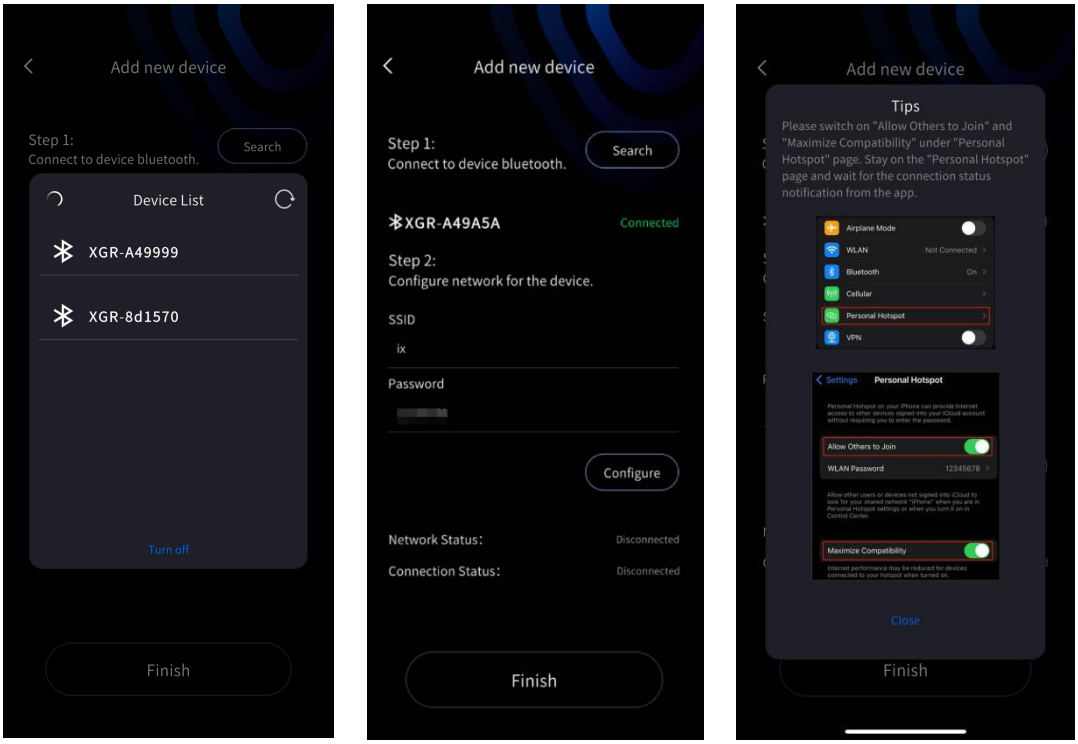

When enabling the hotspot, cellular data (mobile network) must be turned on. (Changing the Wi-Fi connection status will affect the hotspot toggle.)

Only when staying on the "Personal Hotspot" page can you confirm that the phone hotspot is enabled. Also, ensure that the "Allow Others to Join" toggle is switched on to allow devices to connect and discover the Wi-Fi. The hotspot selection must be set to maximum compatibility for successful connection.

Staying on the "Personal Hotspot" page, you will see messages pop out. Only when you see "Data Connection Successful!". You can go back to the LixelGo app.

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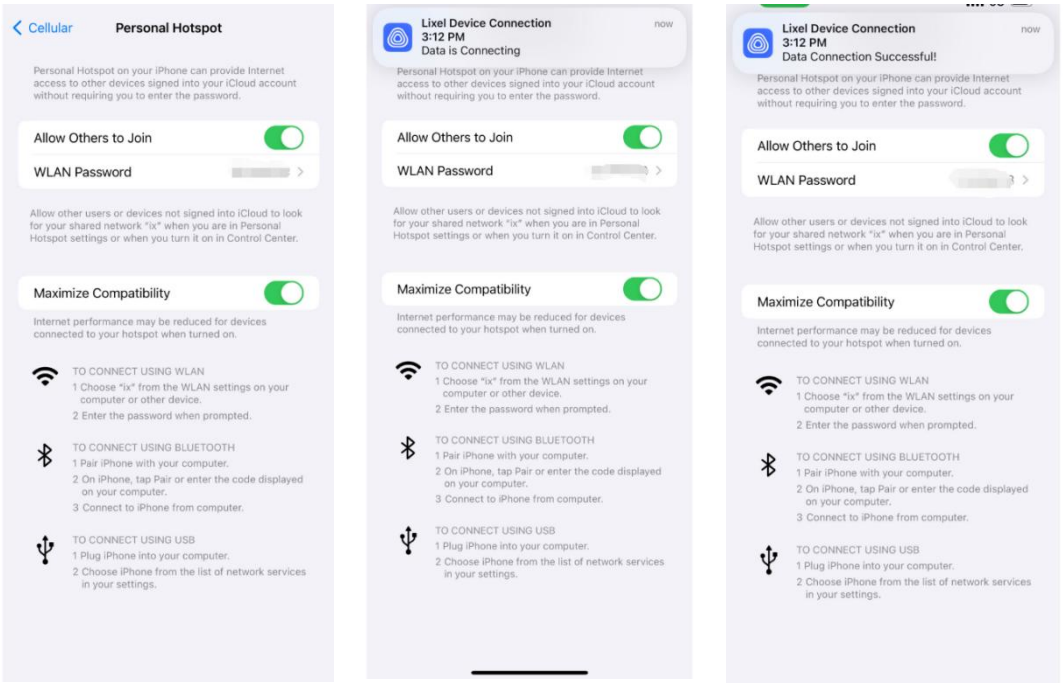
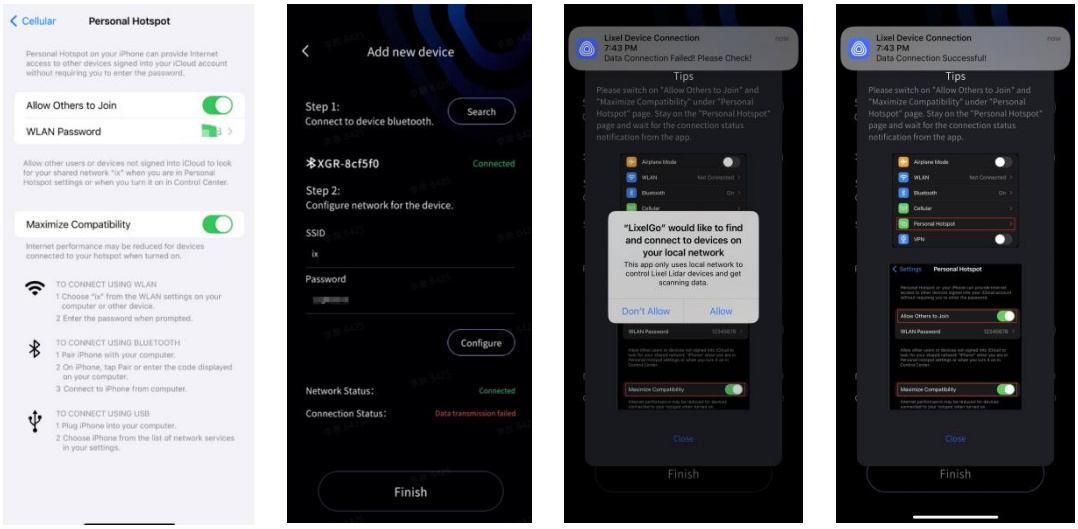


During the first connection, data connection may fail due to permission reasons. After returning to the application, clicking "Configure" will prompt the permission dialog again. Selecting "Allow" will immediately establish a successful connection.



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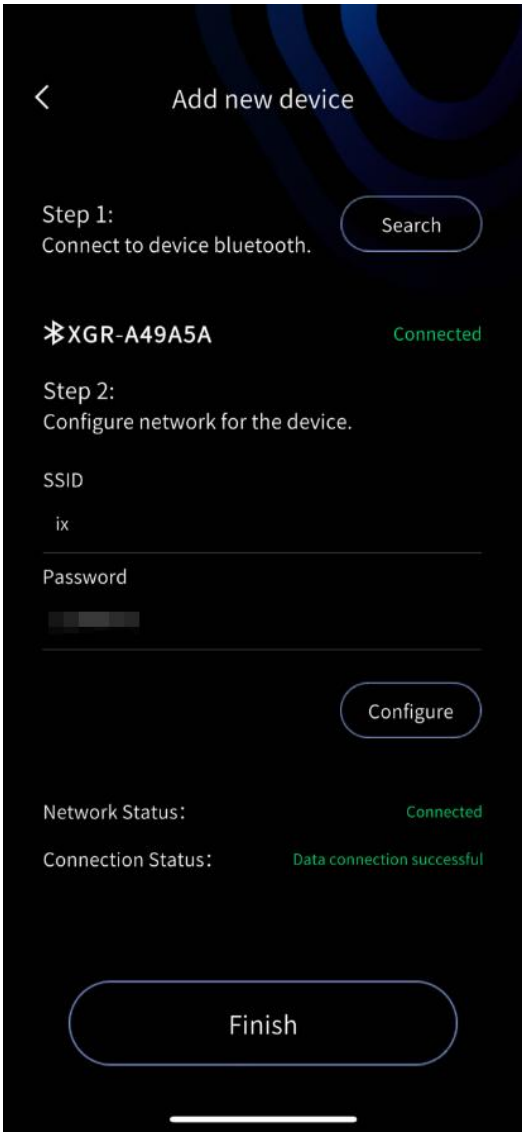

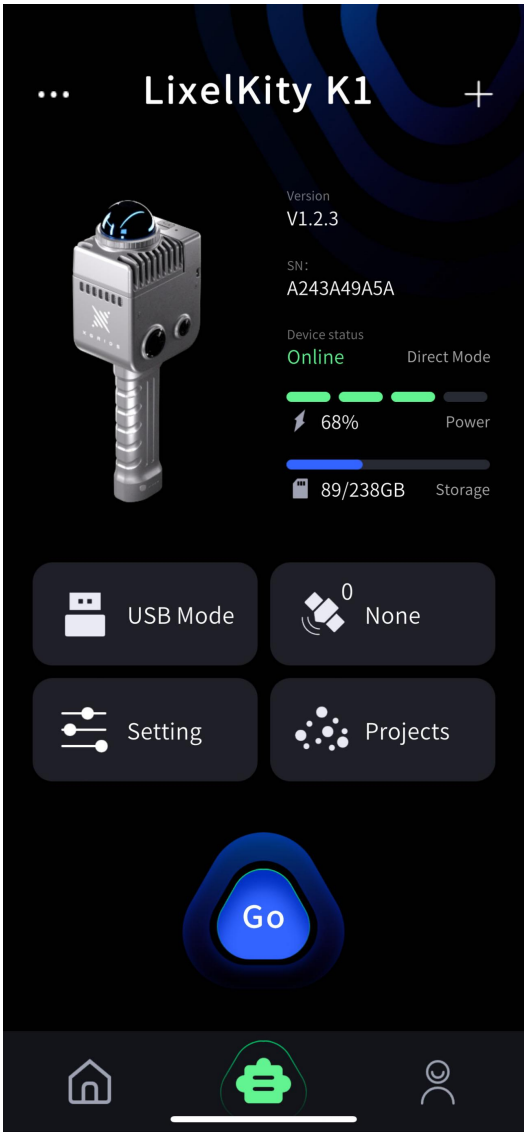

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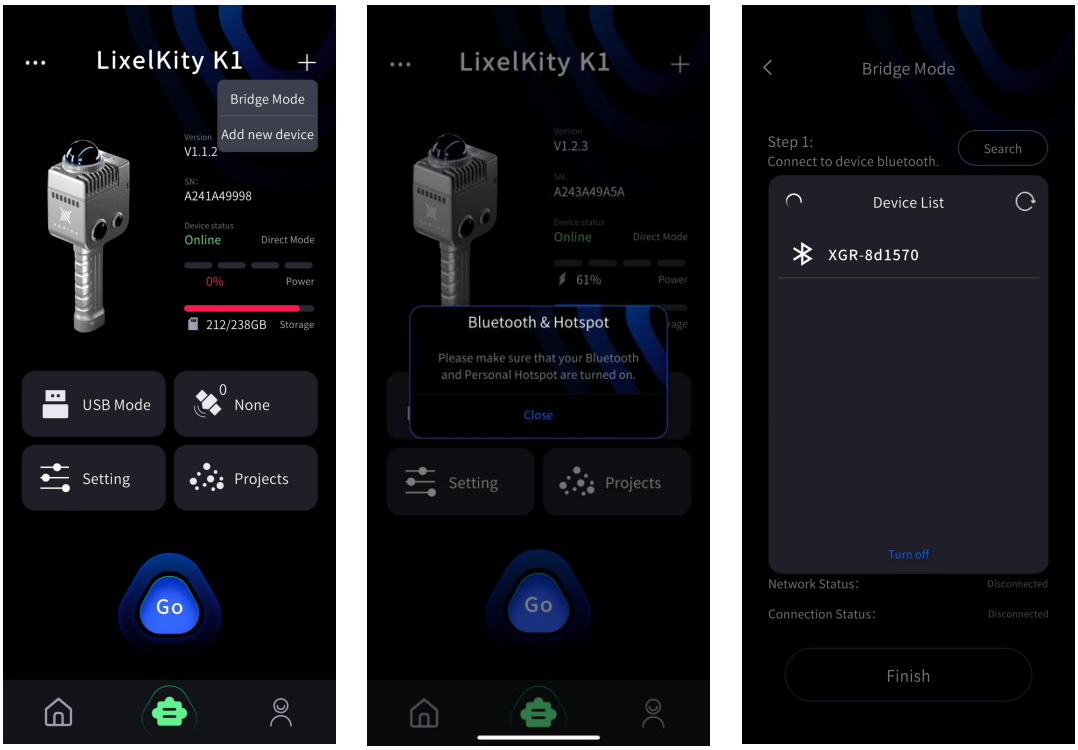
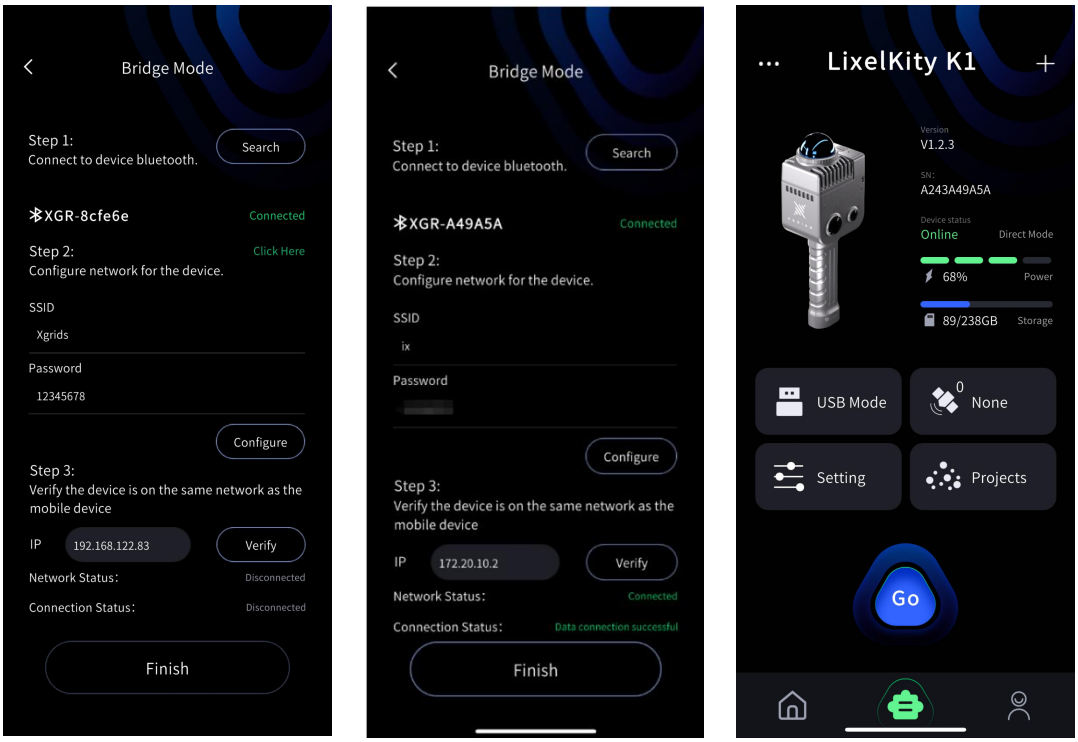


Click "close" and go to the connect page. First search the device's Bluetooth and connect. The second step is to configure the network. See the above steps in direct connect mode for details. After the correct connection, click Finish to view the device's basic information.



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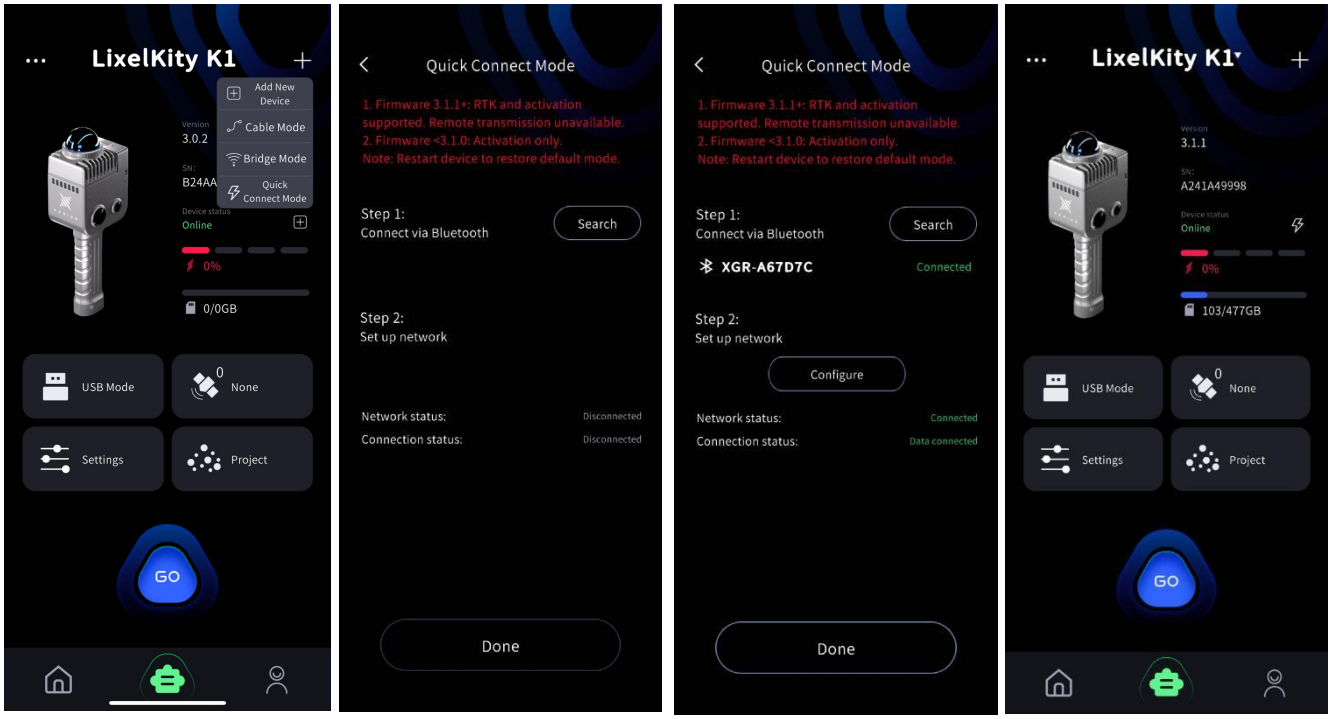
Firmware <3.1.0: Activation only.

Restart device to restore to default mode.



5. Device Management

In the device interface, click and pull down the device name at the top of the screen to manage connected devices. Click Remove Device to remove the connection to the device.

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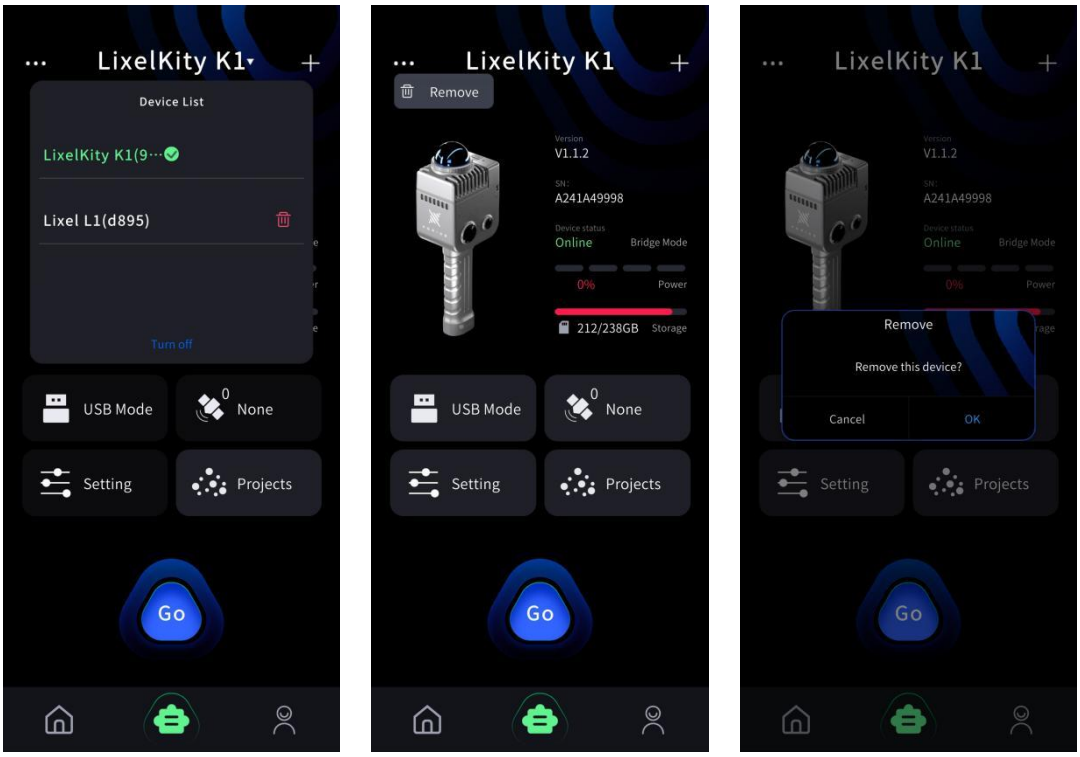

6. Device activation

Click "Go", and confirm the activation and binding of the device.

4 Scanning workflow

4.1 Connected the device

Click "Go" to enter the scanning windows so that the device is to be started.

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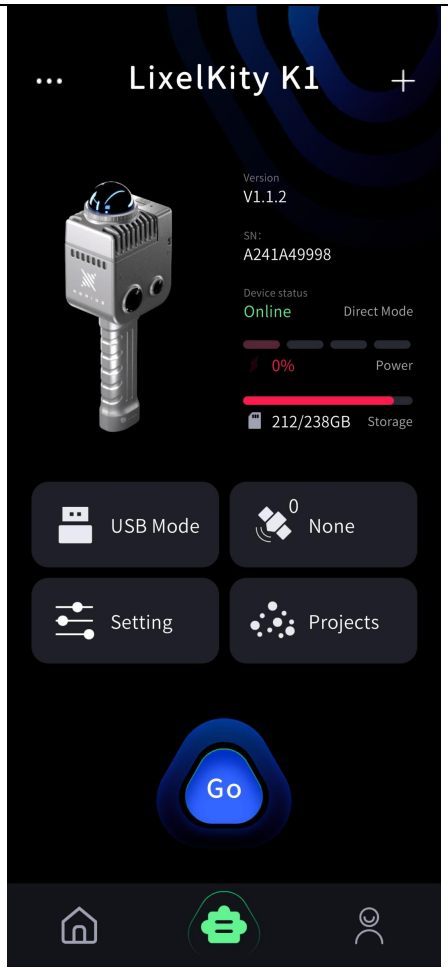

The device undergoes time calibration before leaving the factory, but if it is stored for an extended period, the device's time may become inaccurate. The automatic synchronization switch in LixelGO is turned on by default, which will automatically synchronize the device's time with the time on your phone. Users can also customize the device's time settings through LixelGO. It is recommended that the device's time and time zone match the actual time and time zone of its location.

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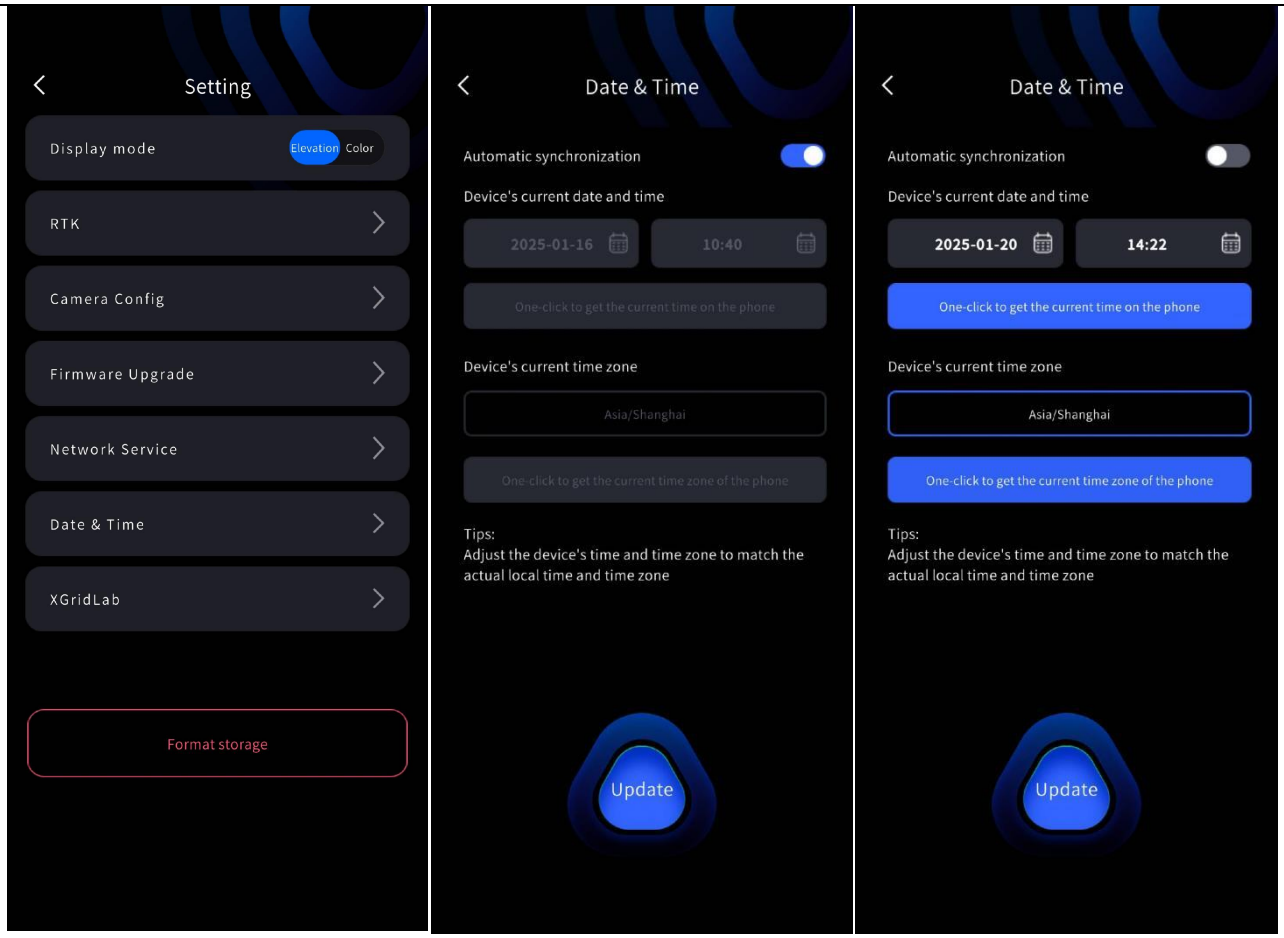

4.2 Scan Mode Settings

Click the red Record button on the right side of the screen and select the appropriate configuration.

GNSS Mode Settings	Function Definition	Description
RTK	The RTK module uses RTK functionality to receive differential data and record it in the project file.	On the startup page, select the RTK mode according to the project requirements. LixelStudio software requires an RTK module for project processing.

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PPK	The RTK module uses PPK functionality to receive raw satellite data and record it in the project file.	On the startup page, select the PPK mode according to the project requirements. LixelStudio software requires a PPK module for project processing.

Mount Type	Function Definition	Description
Handheld	Use in handheld mode.	LixelStudio will automatically read the mount mode, eliminating the need for manual selection during project processing.
Vehicle-Mounted	Use with XGRIDS vehicle-mounted accessories.	LixelStudio will automatically read the mount mode, eliminating the need for manual selection during project processing.
Drone	Use with XGRIDS drone accessories.	LixelStudio will automatically read the mount mode, eliminating the need for manual selection during project processing.

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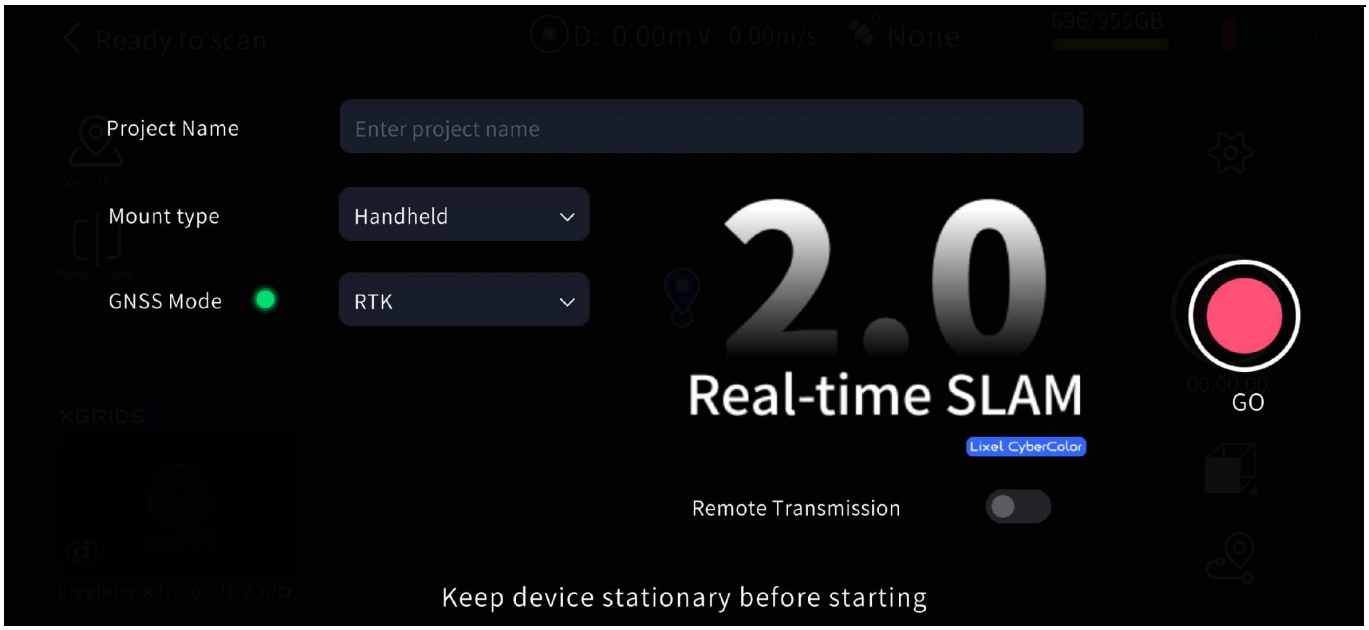

When initiating a scan, an input field for the project name will be displayed on the startup page, and the input field supports multiple languages. If you enter "Parking Lot B2F" and start the scan, after the scan is completed, you will see the project folder named: "Parking_Lot_B2F_2025-01-15-1622026," where "2025-01-15-1622026" represents the scan time. If no project name is entered, the project folder will be named: "default_2025-01-15-1622026."

4.3 Start scanning

After the scanning mode selection is completed, the LiDAR starts working. The indicator light turns green and flashes. And the app prompts that static initialization has started, and then starts a 15s static initialization countdown. During this process, do not move the device to ensure that the device is always in a stable state. After the countdown ends and a pop-up window prompts that static initialization is complete, close the pop-up window, pick up the device, walk around, and start scanning according to the planned route.

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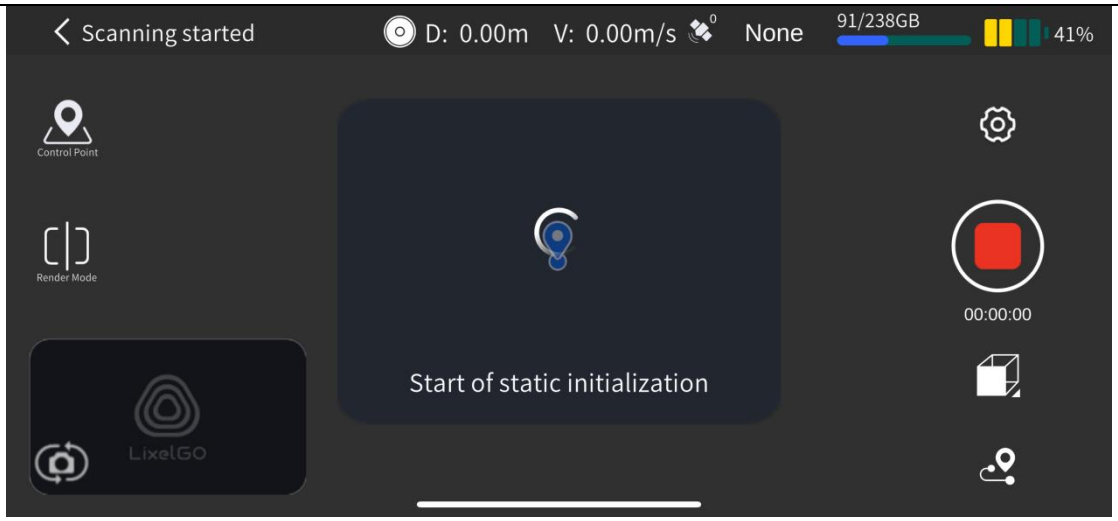

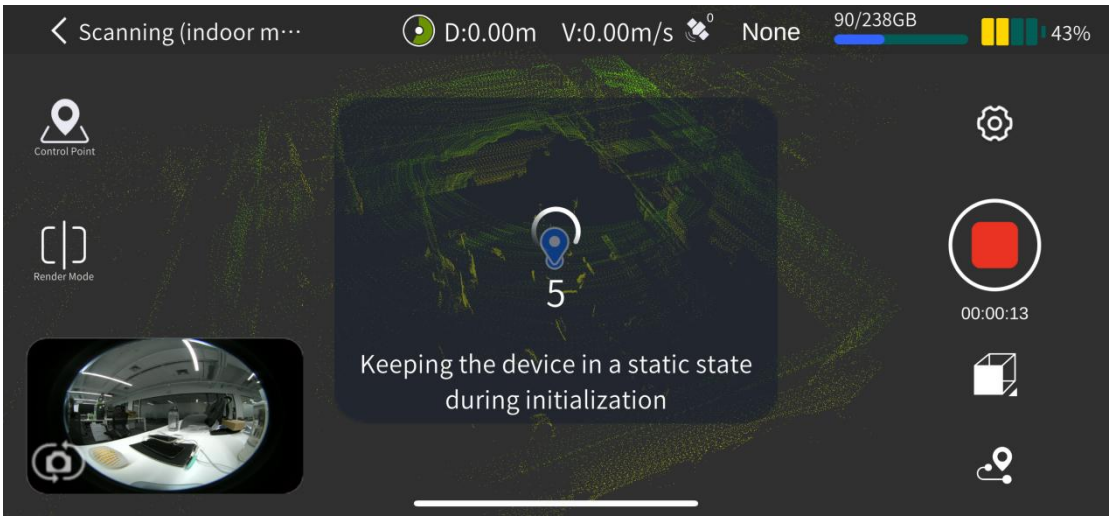

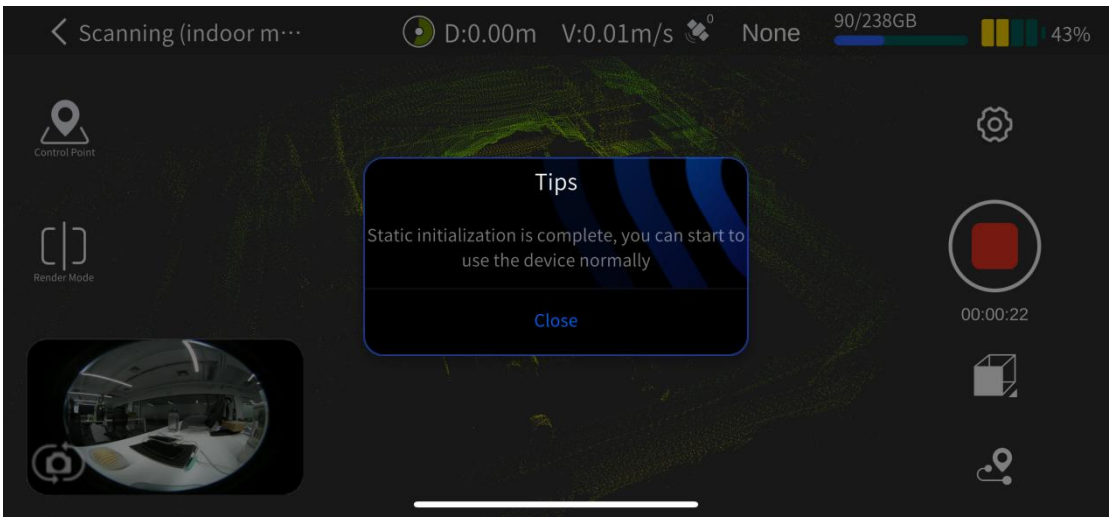

1.Handheld device usage suggestions

When scanning, keep the device away from the body to reduce the proportion of the body in the camera's field of view. For example, lifting the scanner above the head or at the far end of the chest can reduce the proportion of the body in panoramic camera

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view and improve the colorization effect.

The following are four posture situations of the human body proportion in the panoramic camera view. Considering the convenience of mobile scanning, it is recommended to use the first posture.

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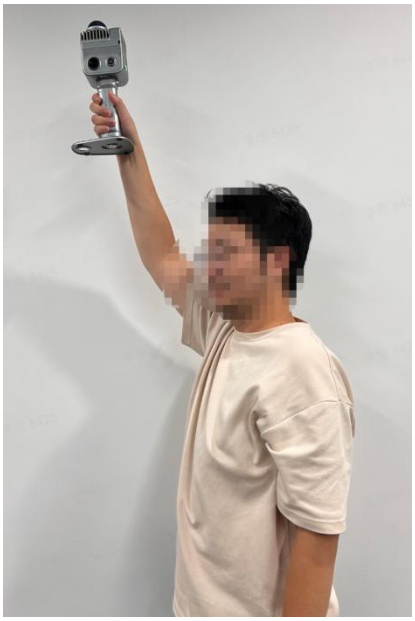

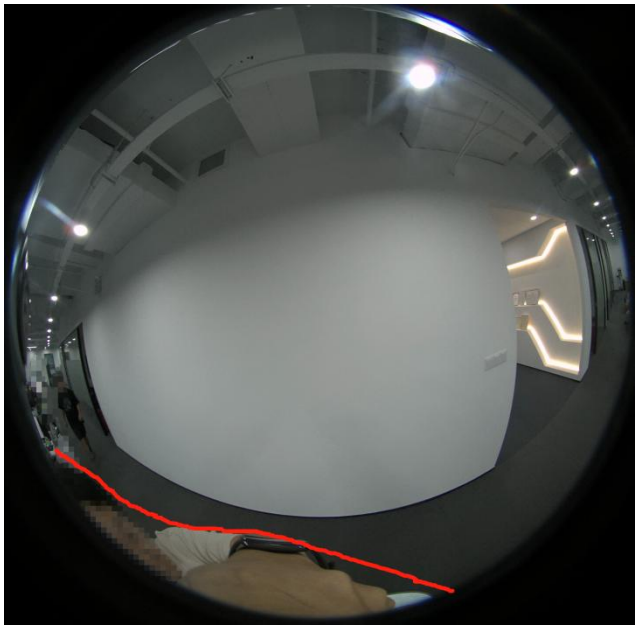

2. Scan route suggestion

When scanning, try to choose a scanning route with a wide FOV. Such as scanning in the middle of the road, which can improve the coverage of the color point cloud and improve colorization accuracy.

When acquiring color point clouds in some small space scenes, such as the gap between buildings in urban villages, narrow roads in alleys, etc, mobile scanning needs to be slower than normal walking, and posture 4 needs to be used if necessary. And it even needs to be scanned in the condition that there are no other shadows or dynamic

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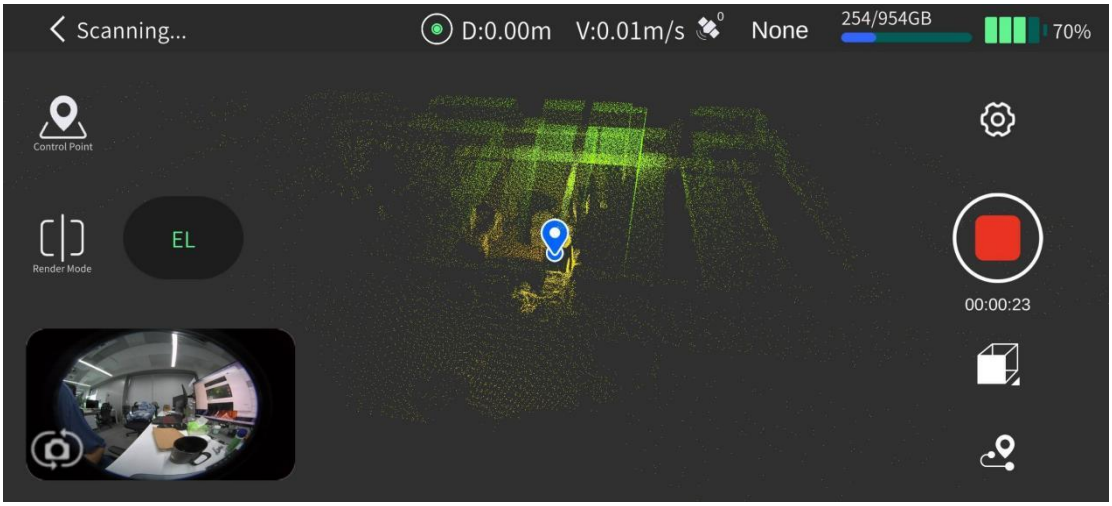
objects in the scanning process, in order to obtain the correct and better colorization effect point cloud.

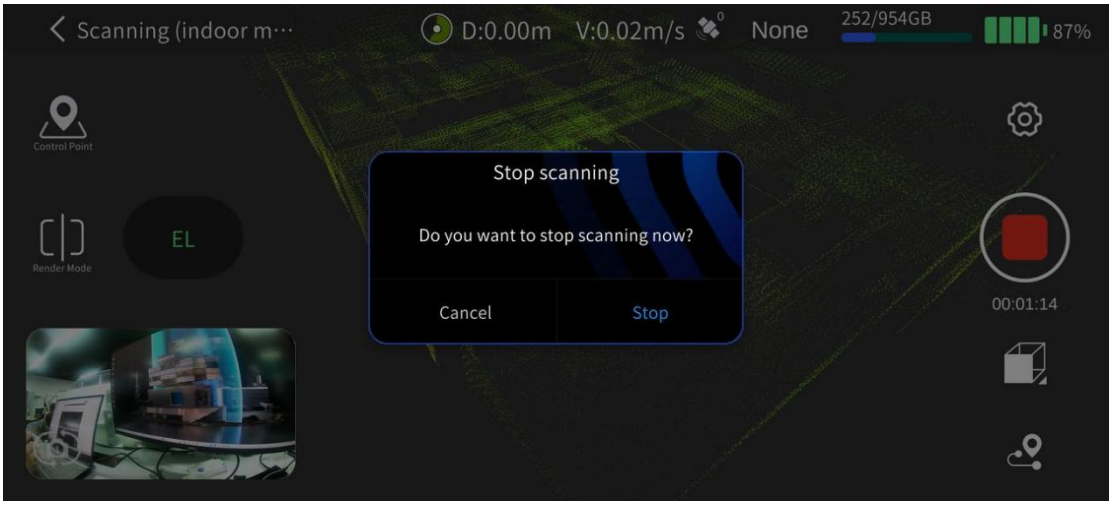
4.4 Rendering mode

Click the "Render Mode" button on the left side of the screen to modify the real-time point cloud rendering method. Currently, there is one mode available: " EL " - elevation.



4.5 Stop scanning

Click the red Record button on the right side of the screen. After confirming the stop, the device's green light will flash, and the device will turn green and stay on after the scanning is completed. Then you can shut down the device or start the second scan.



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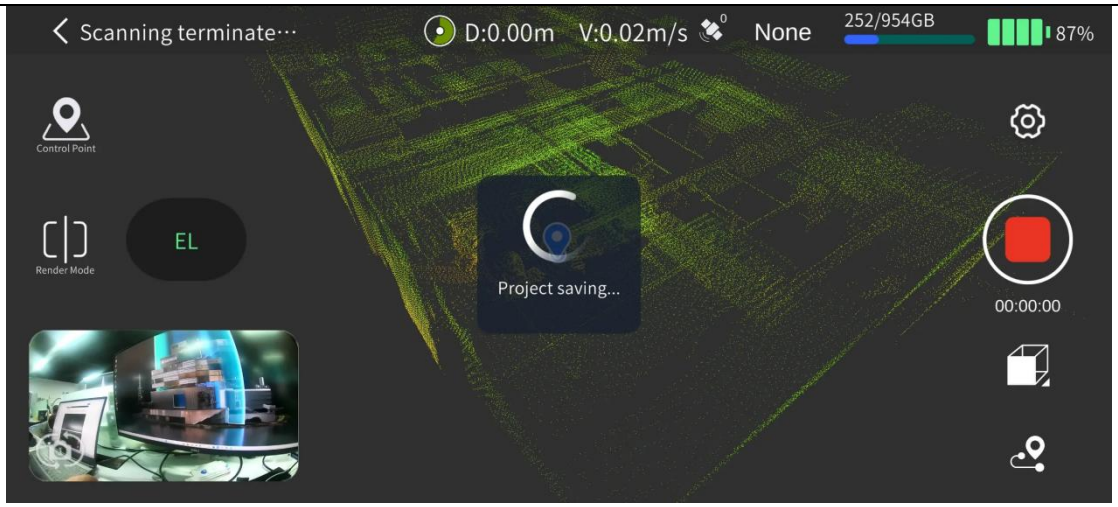

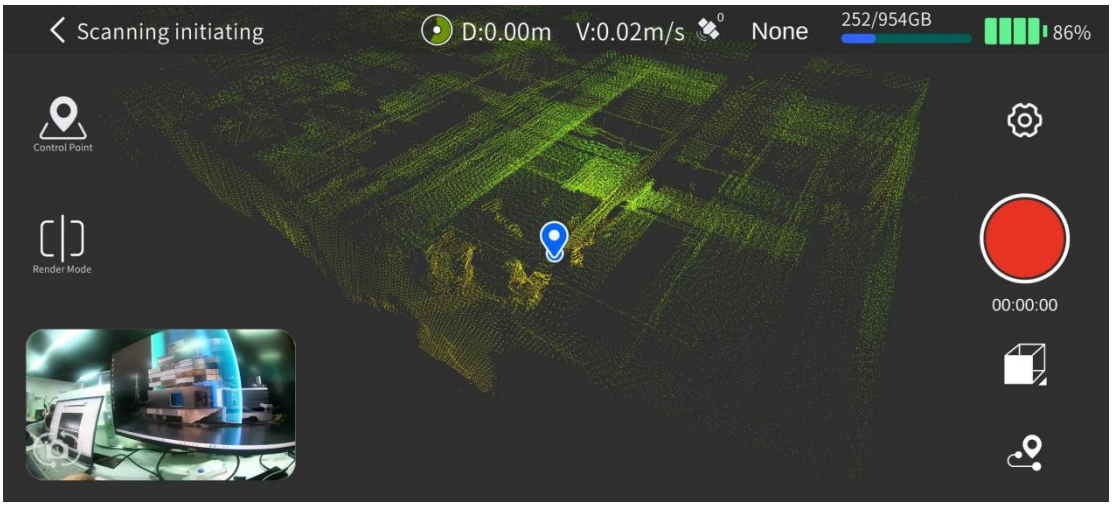

4.6 Downloading scan data

Turn on the device, set the device to USB mode in the app, and then use a Type-C cable to connect the device to the computer.

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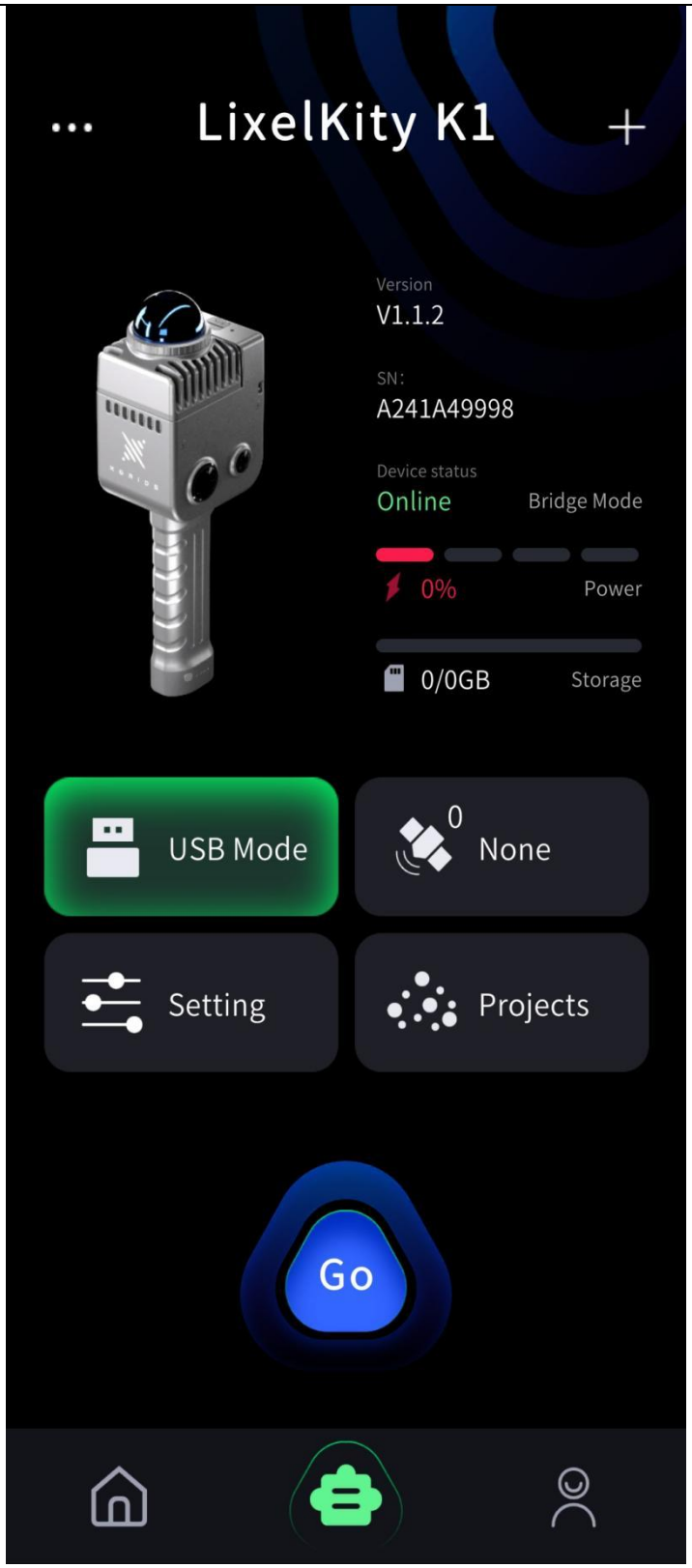

In the model file in the directory of USB disk mode, select the corresponding project file . And you can copy it to the appropriate directory of the computer. The project files name after the time of scan starting: ProjectName-year-month-day-specific time

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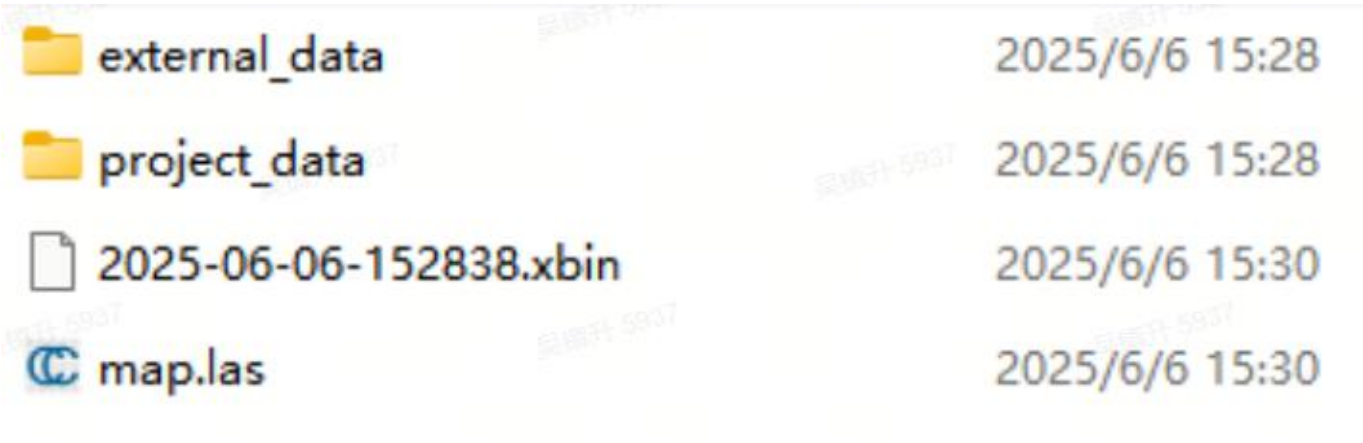
4.7 Data project file structure

.hbc is the raw sensor data recorded by the device.



File or folder name	Files in the subdirectory	Introduction
xxx.xbin	-	raw sensor data recorded by the device.
map.las	-	the point cloud data directly output by the scanning device in real time.
project_data	control_points.csv	A file that records control point information when using the app to add control points.
	gnss.csv	A file that records GNSS information when using RTK.
	poses.csv	Record the trajectory file during the scanning process.

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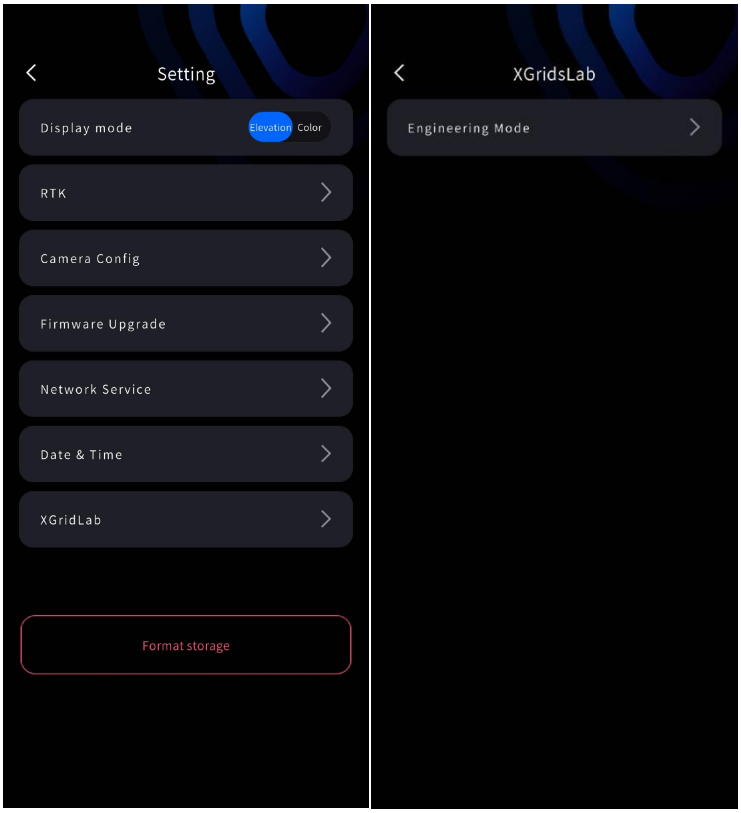
	project.json	Record device-related information.
	log	The log folder records the relevant log information of the device.
external_data	-	This folder is empty when the data is initially copied from the handheld device. It is mainly used to copy and store external file data required for post-processing in LixelStudio, such as video files of external panoramic cameras and gnss.csv files after coordinate conversion.

Please note: The direct point cloud data is downsampled. If you need complete point cloud data, please use LixelStudio software for post-processing.

4.8 XGRIDS LAB

This feature is part of the XGRIDS LAB. XGRIDS Innovation will place specific experimental functions into the XGRIDS LAB for testing in special environments.



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5 Acquire point cloud data with absolute coordinate

5.1 Through existing Ground Control Points (GCP)

You can achieve coordinate conversion through the existing Ground Control Points (GCP) you marked during the scan, by which the accuracy of the point cloud data can be optimized as well.

Note: The number of control points in the sacnning area is determined according to the accuracy requirements. And the layout of control points should be evenly distributed. To ensure subsequent coordinate conversion to be successful, at least 3 or more control points reasonably distributed are required for a single scan. The more high-precision control points covered by scanning, and the more evenly distributed, the higher the accuracy will be. Do remember the points cannot be distributed on a straight line.

1.Scanner installation

Equipment list include LixelKity K1 Handheld Scanner, battery, control Point Base, Installation diagram is as follows:

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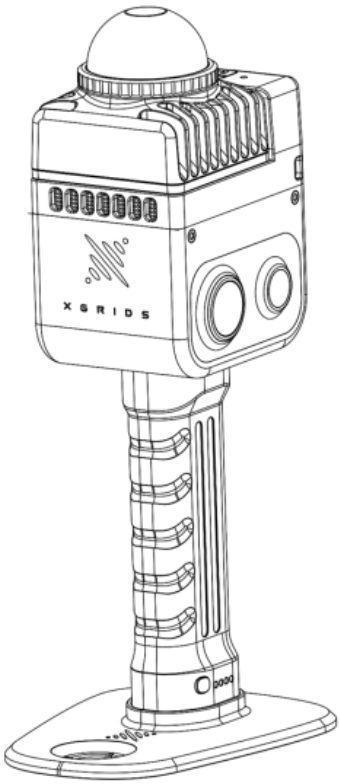

2. Field work: scanning

Field survey and planning

If there is a corresponding topographic map of the scanning area, the control points can be designed according to the map, and the on-site inspection and design can be carried out synchronously. If there is no corresponding topographic map, the design will be carried out according to the on-site environment.

The distribution of control points should be as reasonable as possible, which means evenly distributed in the scanning area. And the distance between control points should be within 50 meters.

According to the distribution of control points and scanning environment, plan a reasonable scanning route.

Start scanning

Turn on the scanner, and start scanning through the LixelGO or the button on LixelKity K1. For specific steps, please refer to the Scanning Workflow.

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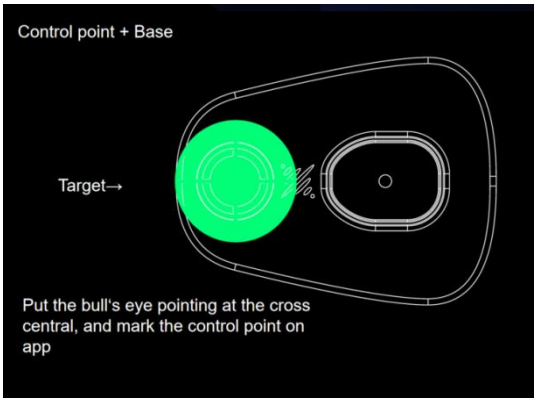
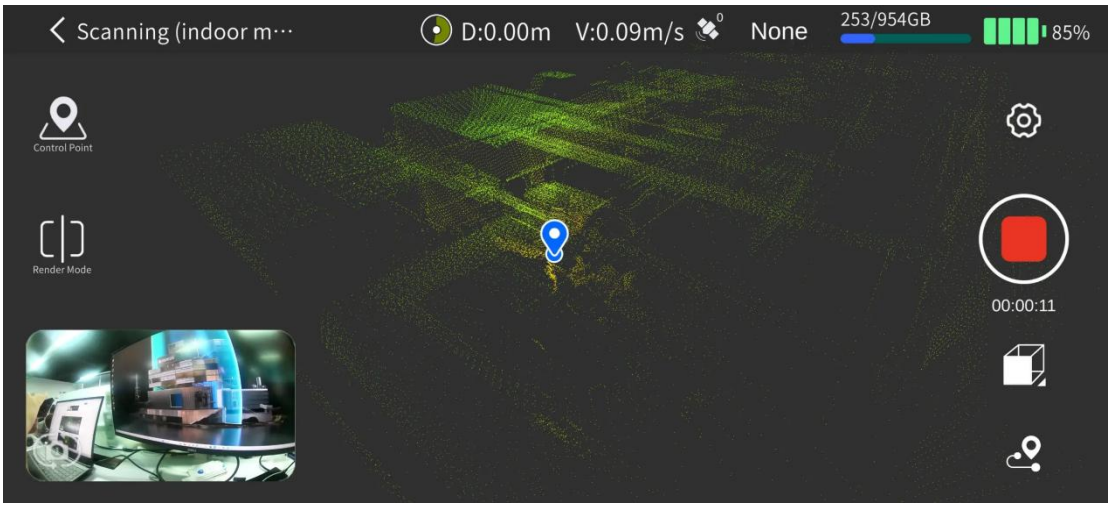
Mark the ground control points (GCP) during the scan

When scanning on the route across the areas covering the control point, align the sharp corner of the front end of the scanner control point base with the control point, and then click to add the control point in the LixelGO.



Click "Control Point Mode" on the left side of the screen.



Click "+" on the left side of the screen to add a control point.

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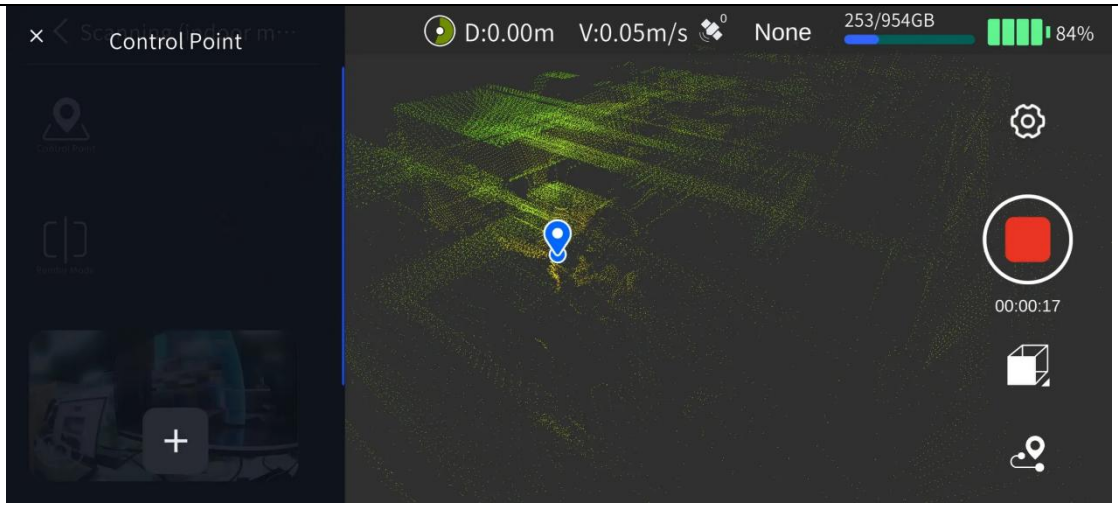
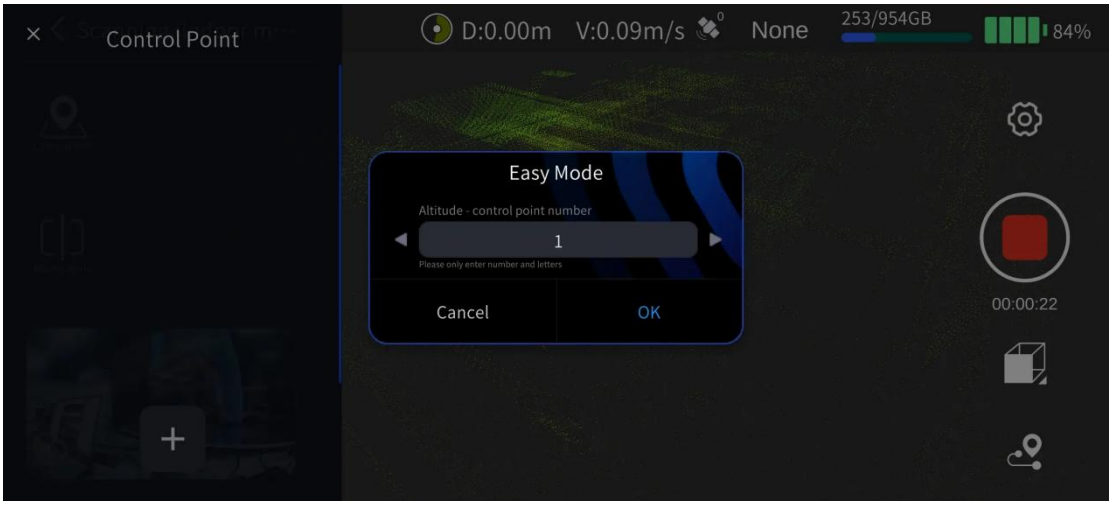
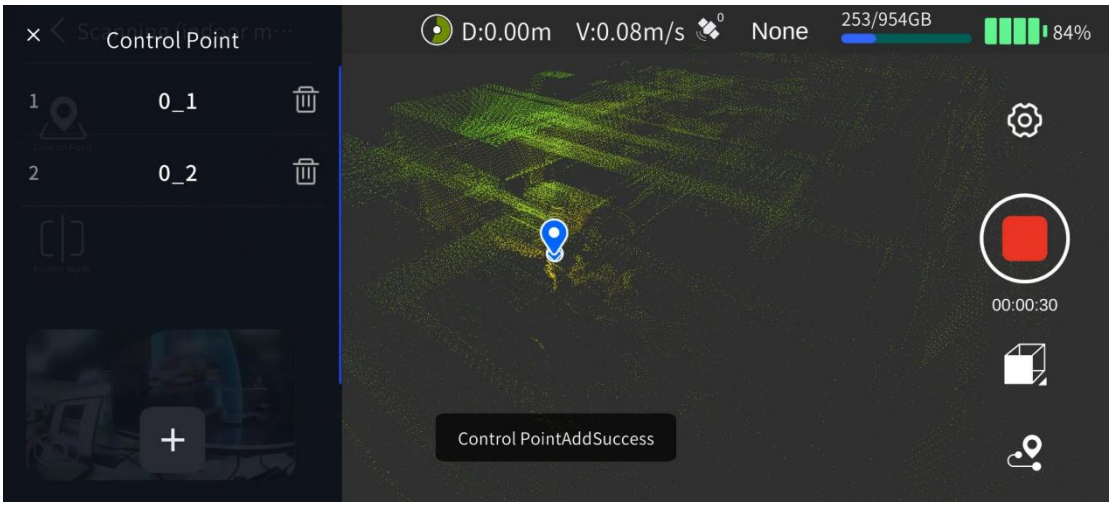


Enter the control point number, then click OK, and the screen will pop up "The control point was added successfully", indicating that the control point was successfully marked.





Pay attention to the names and order of the control points marked on the LixelGO when tapping. When you do the processing in LixelStudio later, you need to ensure that the file names of the imported control points correspond to the names of the control points

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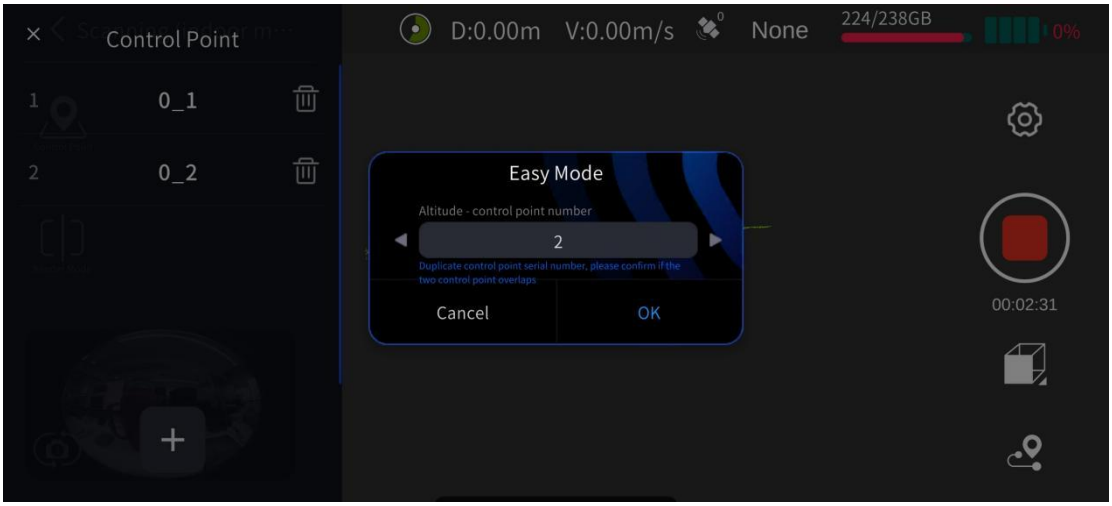
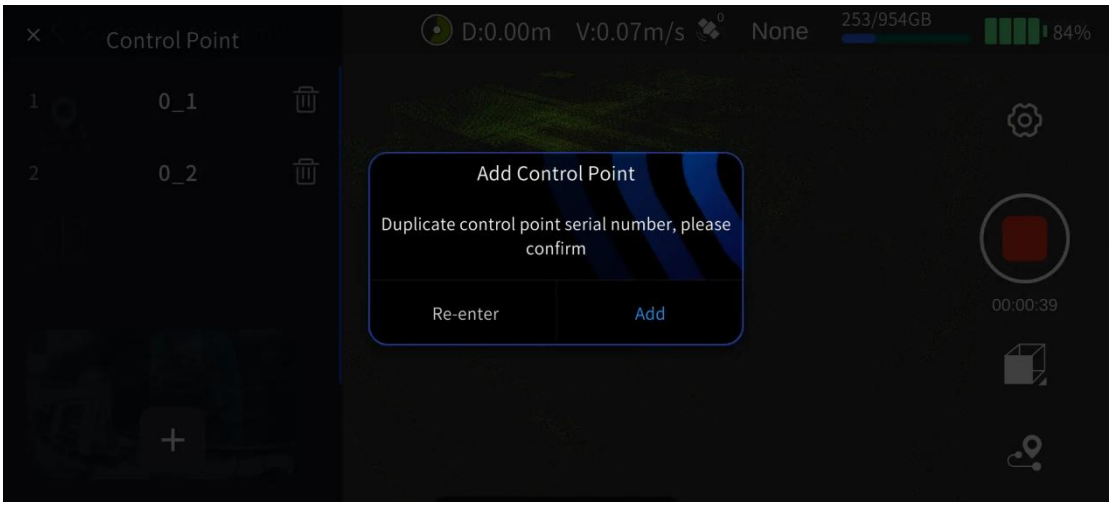
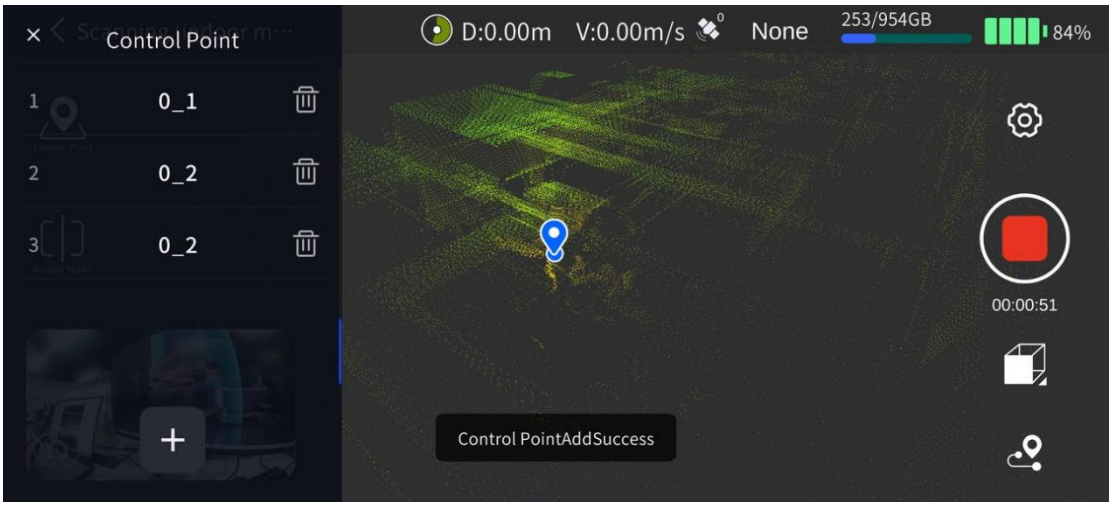
marked during the scan.

If the name of the added control point is repeated, the LixelGO will pop up a reminder, please judge and and modify it according to the specific situation.







You can view the collected control points and delete control points in the "Control Point

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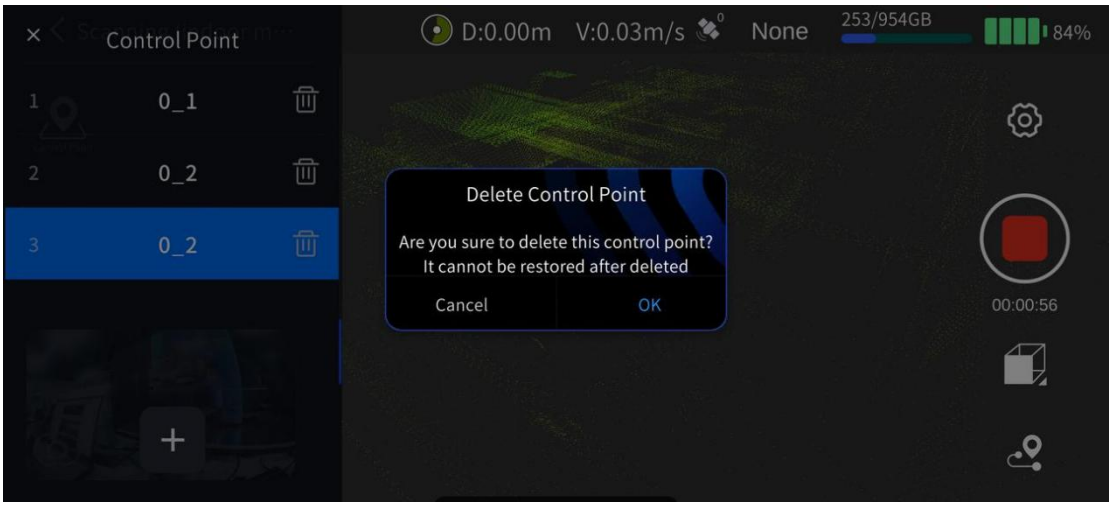
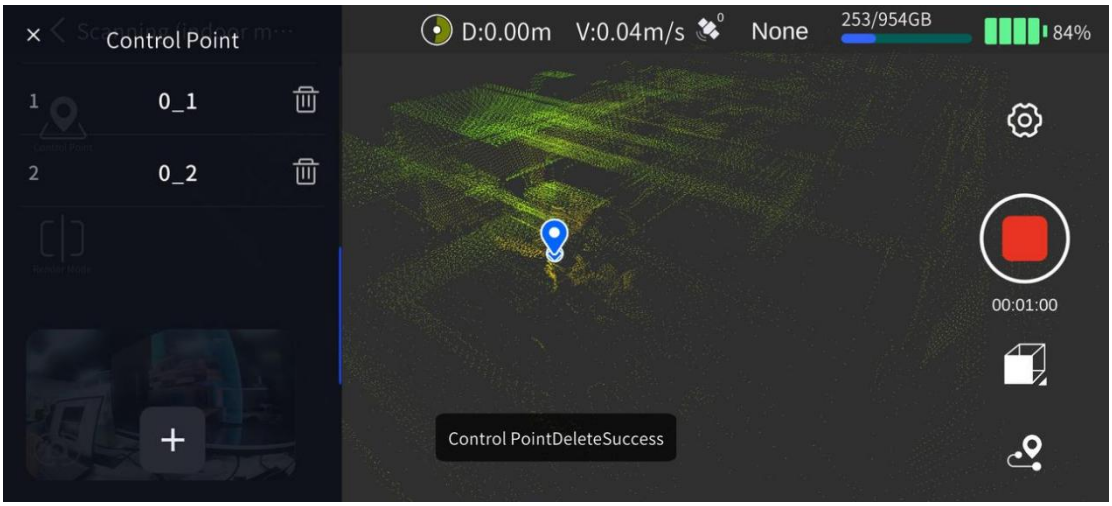
List" on the left side of the plane. Click the Delete button on the right side of the control point to delete the corresponding control point.





Stop scanning

Click the red End Recording button on the right side of the screen, the green light of the device flashes, and the indicator light turns green and always on after scanning. Then you can shut down the scanner or start a second scan.

3. Office work: data processing

See the LixelStudio user manual for details.

5.2 Through the RTK module

With the RTK module, absolute coordinate information can be directly obtained during the scanning process, and the overall accuracy of point cloud data can be improved.

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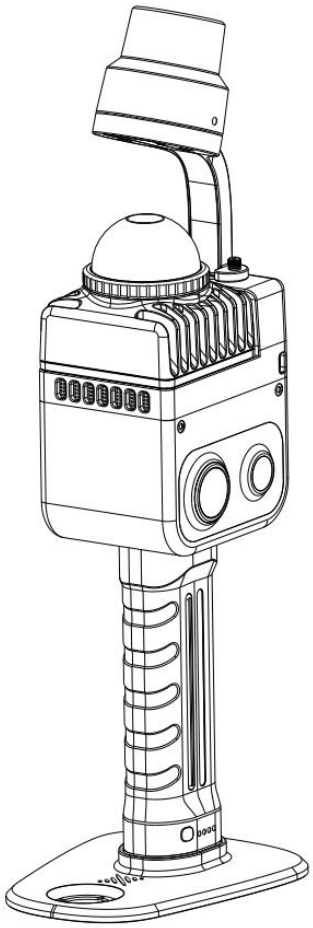
Note: In order to ensure good performance, please use this mode to scan when the outdoor RTK signal is good.

1. Scanner installation

The installation components include LixelKity K1 Handheld Scanner, battery, base, RTK module, RTK bracket.



Note :

RTK module indicator lights have three statuses: red, blue and green.

Red: RTK not connected; Blue: RTK connected, not fixed; Green: RTK connected and has a fixed solution.

2. Field work: scanning

Scan route planning

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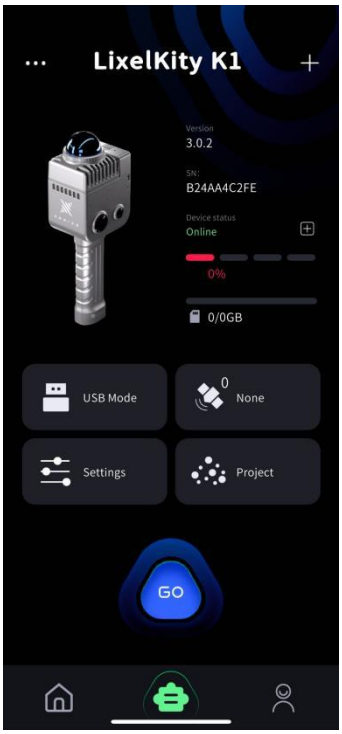
According to the scanning environment, plan the scanning route reasonably, and ensure that the RTK signal is good during the scanning as much as possible. If you need to ensure the accuracy of point cloud after processing in LixelStudio, please ensure that RTK with no fixed solution does not exceed 50m during the scanning.

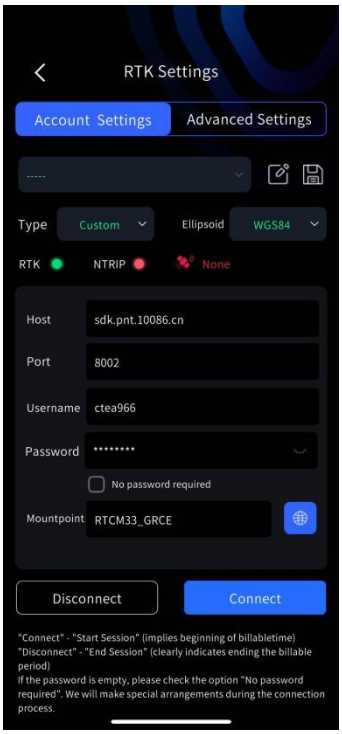
Connect the device

Turn on the scanner and connect the scanner through the LixelGO App. For specific steps, please refer to the Scanning Workflow.

RTK Account Settings

Enter the device windows, click RTK settings (satellite icon button), enter RTK settings. Currently there are 3 types of RTK configuration, custom, Qianxun SI, and China Mobile. Users can configure it according to the specific situation in different areas. Custom setting is as follows.





Qianxun SI and China Mobile: Users can log in by entering the corresponding account and password.

Account Management

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When there are single or multiple frequently used accounts, RTK account information can be saved to the LixelGO app cache via the "Save" button.

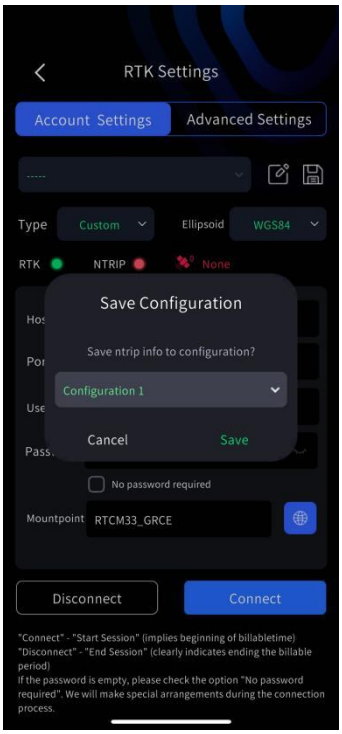
Operation Steps

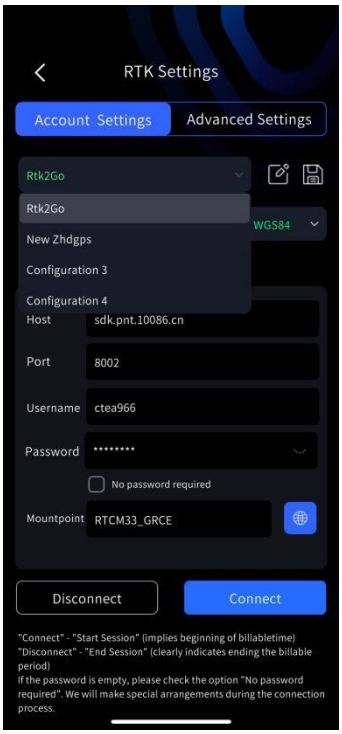
1.Enter RTK account information, including host, port, source node, etc.

2.Tap "Save", then select a configuration item to save in the pop-up window. The RTK account information will be saved to the LixelGO app cache.

3.Tap "Edit" to modify the configuration item name. After saving, the RTK account configuration name will be updated.

4.Saved configuration item information can be viewed in the drop-down menu.





Attention :

1. Currently, it supports Qianxun SI, China Mobile and custom RTK . To use a custom RTK,

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you need to ensure that the RTK data format is a common format, otherwise it cannot be used normally

2. The first time the device and RTK account are set up, the RTK account information will be automatically recorded, and subsequent use will be automatically logged in.

3. If you want to change the RTK coordinate system, there will be a delay of about 5 minutes. It is recommended to start the operation after the change for 5 minutes

4. At present, RTK module is adaptive to WGS84, CGCS2000 and ITRF2008 reference coordinate system. And the height acquired is geodetic height.

RTK Advanced Settings

GNSS Mode Settings

GNSS Mode Settings	Function Definition	Description
RTK	Real-time differential correction from the RTK module recorded in the project file.	On the startup page, select the RTK mode according to the project requirements. LixelStudio software requires an RTK module for project processing.
PPK	Post-processing correction using raw satellite data.	On the startup page, select the PPK mode according to the project requirements. LixelStudio software requires a PPK module for project processing.

Satellite System Setting

Customize satellite system selection with single, multiple, group selection, or select all options.

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Requirements

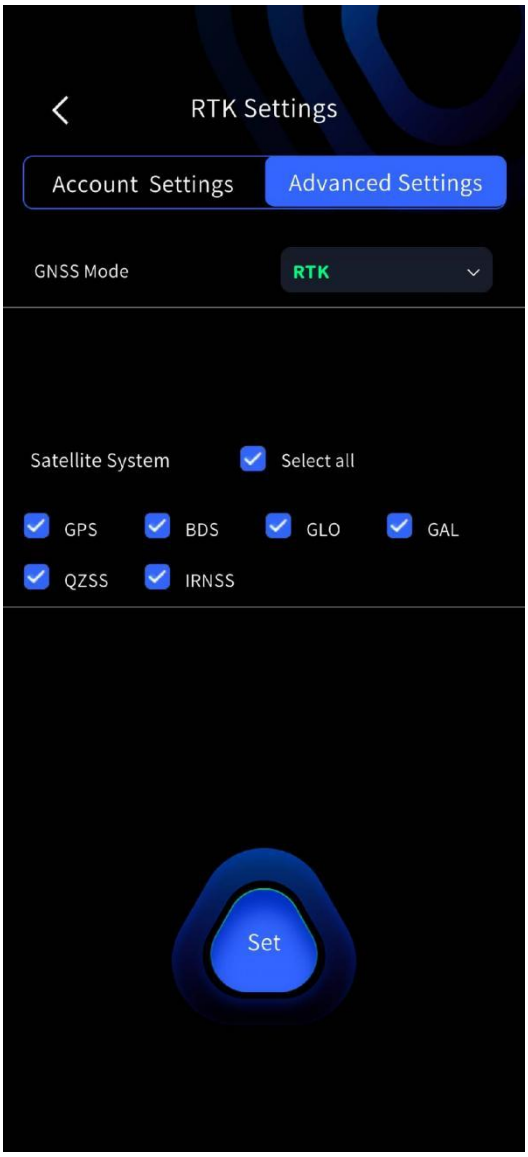
Firmware version 2.3.0 or above.

The RTK module is connected to the scanner.

Satellite System Options

Device satellite system settings will be automatically read and displayed under Advanced Settings.

Select one or more satellite systems, or select all. Tap "Set" to apply immediately.



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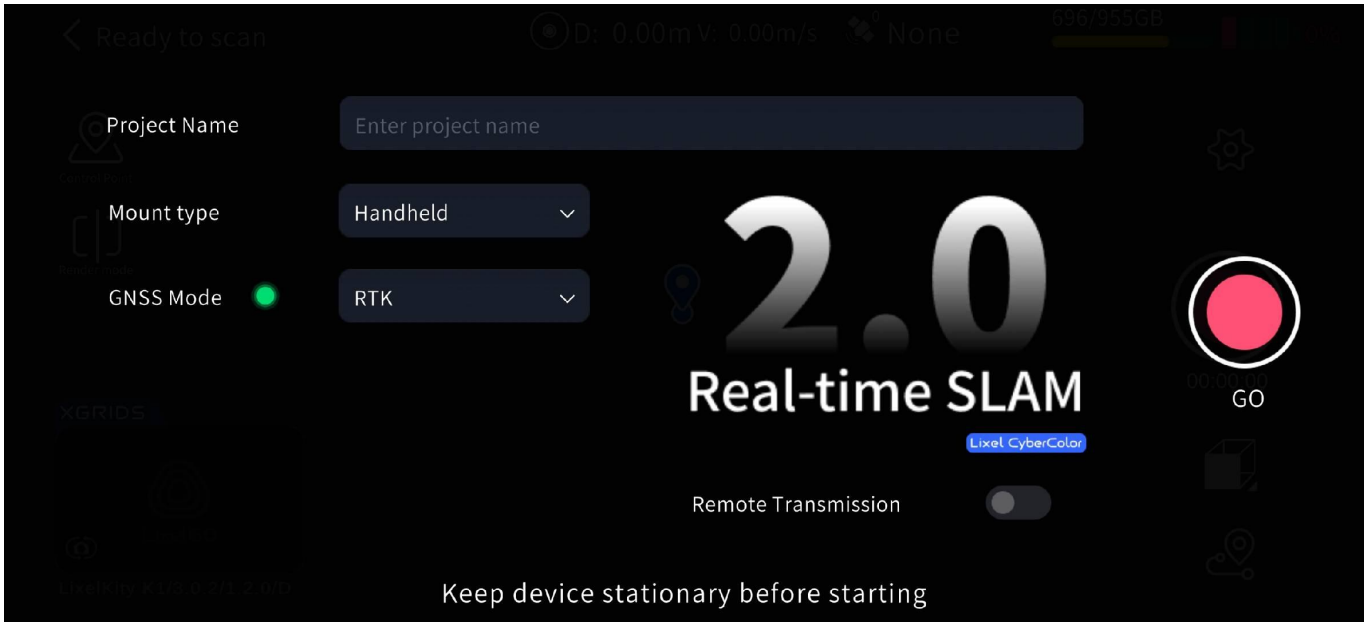
Start scanning



In RTK mode, you need to wait for the RTK module indicator light to turn green, and the LixelGO displays that the RTK signal becomes Fixed before picking up the scanner and starting the scanning operation.

Attention :

1. RTK mode only supports scenes with RTK signals outdoors. RTK will not be able to obtain a fixed solution in indoor scenes.

2. During the RTK fixed solution, the RTK module indicator light turns green. If the light turns blue, pay attention to the satellite number.

3. Only if the satellite status on the LixelGO is fixed, you can start the scan. It can not be NONE, float, or single.

4. In order to ensure accuracy, it is recommended to make it sure that the device is in a fixed solution state most of the time during the scanning process. It is necessary to ensure that the RTK valid data is > 100 to achieve coordinate conversion successfully in LixelStudio.

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5. When scanning, keep the scanner vertical and avoid tilting. When walking, the inclination angle of the scanner generally does not exceed 20°. In special cases, such as when scanning a small space or ground targets, the inclination angle of the device should not exceed 30°.

6. Pay attention to the scan space, and ensure that the scanning range is above 10m.

Stop scanning

Click the red End Recording button on the right side of the screen, the green light of the device flashes, and the device turns green and always on after scanning. Then you can shut down the scanner or start a second scan.

3.Office work: data processing

See the LixelStudio instruction user manual for details.

6 Map Fusion

When there are effective control points and RTK data, multiple point clouds project can be seamlessly merged automatically. When there is absolute coordinate information, absolute coordinates can also be converted for point clouds. It can avoid overlapping area layering caused by RTK or control point accuracy problems when using global optimization alone.

6.1 Field work: scanning

Refer to "5 Acquire point cloud data with absolute coordinates" for specific operation.

Other notes :

1.For map fusion, no matter using control points or RTK data, in order to achieve better fusion effect, there should be as much overlapping path of a certain length between the two adjacent fused maps as possible. It is recommended that the overlapping path length should be >15m, and 15-30m is recommended. And the adjacent overlapping areas should be in scenes with rich features as much as possible, and avoid degraded scenes such as open space, long corridors, and smooth tunnels.

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2.When using control points, when the control points are with referenced coordinates, make sure that there is a scanning overlap area of >15m between adjacent projects. If the control points do not have referenced coordinates, while ensuring there is a scanning overlap area of >15m between adjacent projects, it is necessary to effectively record the control points in the overlapping area, and ensure that the position and name of the equipment are consistent when two projects use the same control point.

3.Minimum requirements for coordinate transformation: there must be a connection between all maps (relative control points or ground control points), and the number of ground control points with referenced coordinates in all maps is at least 3 or more (and the control points are not in a straight line).

4.If the requirements are not met, data fusion cannot proceed normally.

6.2 In-house: data processing

See the LixelStudio user manual for details.

7 Route planning suggestions for typical scenes

7.1 Principles of the overall scanning route

1. Ensure as many features as possible during the scanning process.

2. Avoid scanning new areas all the time, and making some loops as much as possible.

3. Avoid the impact of dynamic objects as much as possible.

7.2 Outdoor scenes

Typical scenarios: parks, campuses, buildings, etc

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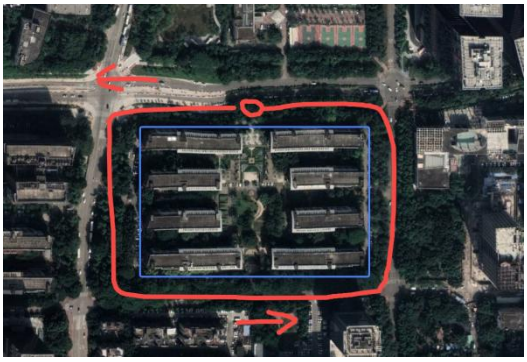
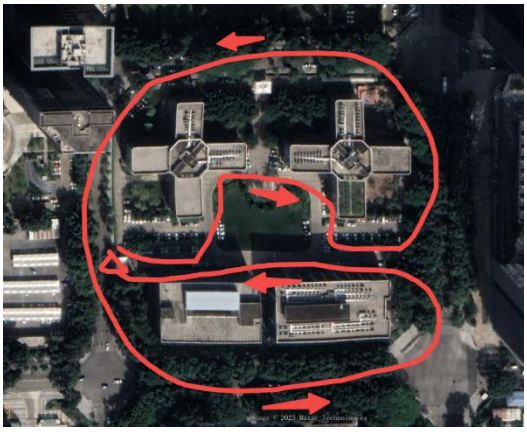
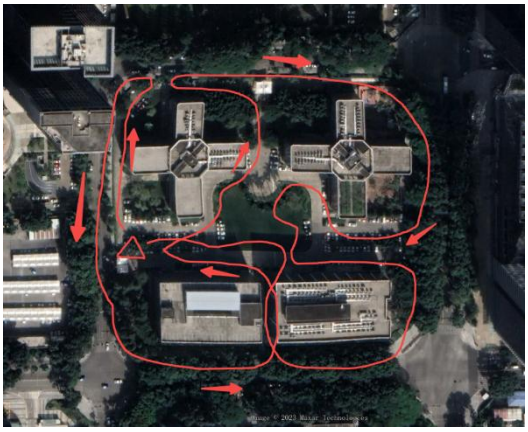


Not recommended route

Recommended route



Not recommended route



Recommended route

7.3 Indoor scenes

Taking common office as an example

1. Route planning

1. Such as indoor parking lots those are more than one floor, it is recommended to scan from top to bottom and snake around.

2. The control point recording method is consistent with the parking lot scene, and the absolute coordinate control point is selected to record with the core area.

2. In and out

Error example: Entering through the door from the front will make the indoor and

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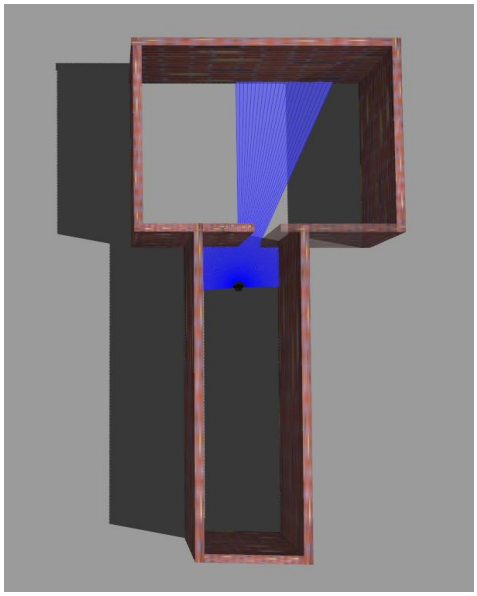
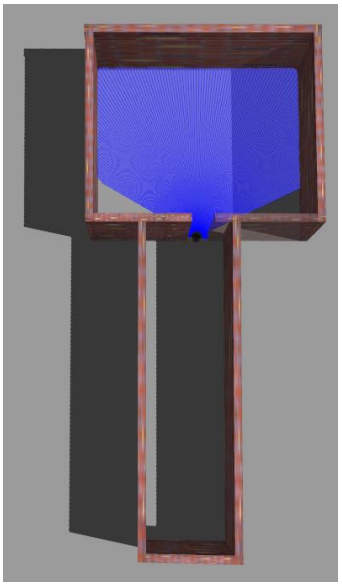
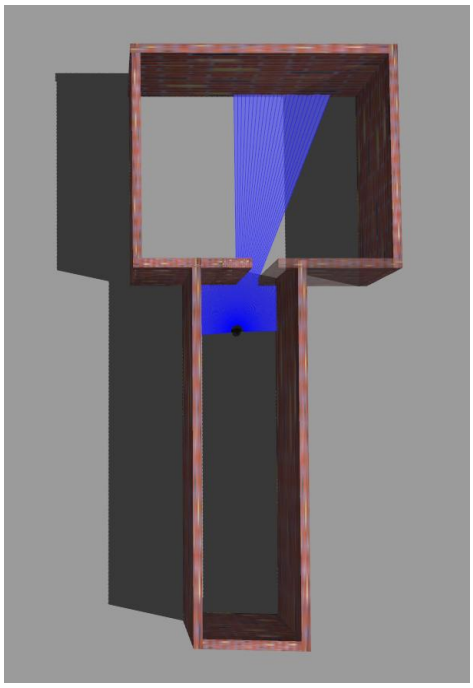
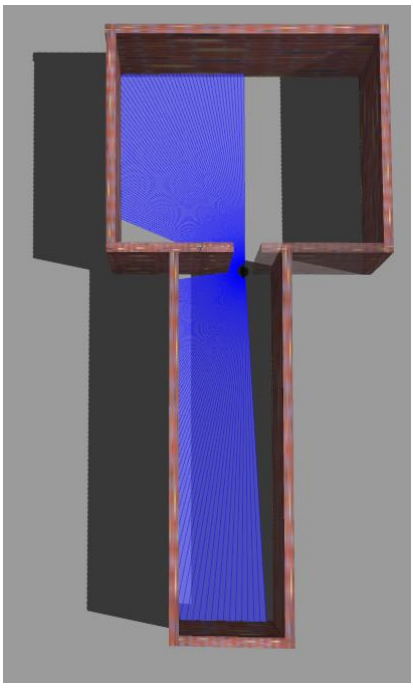
outdoor laser point cloud data lose the common FOV, lose the reference, and cause the data to be skewed.





The correct example is to get through the door sideways to ensure that the indoor laser point cloud and the scanning field before entering the door have a common FOV, better connection, indoor and outdoor data.





3. Hanging corner

Error example: Go straight ahead resulting in the loss of the wall view in the lower left

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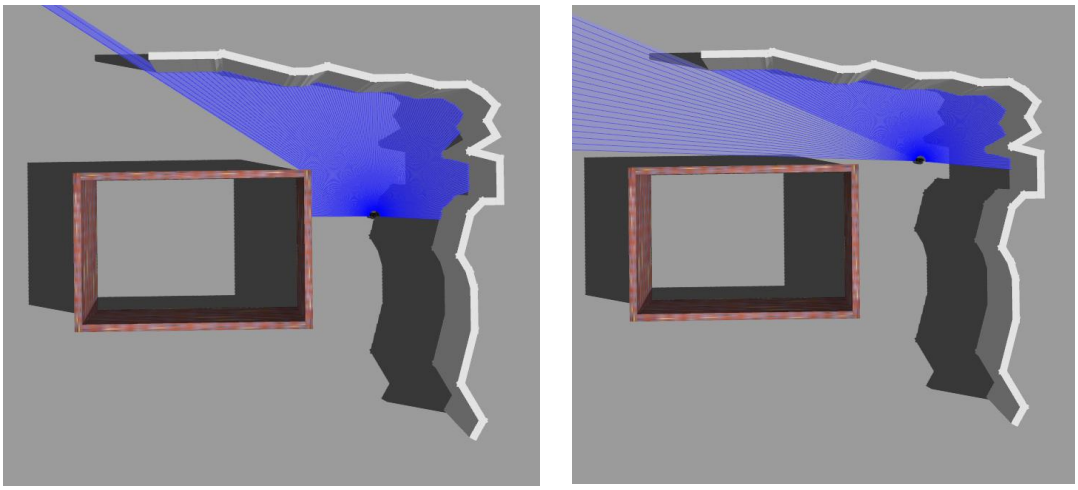
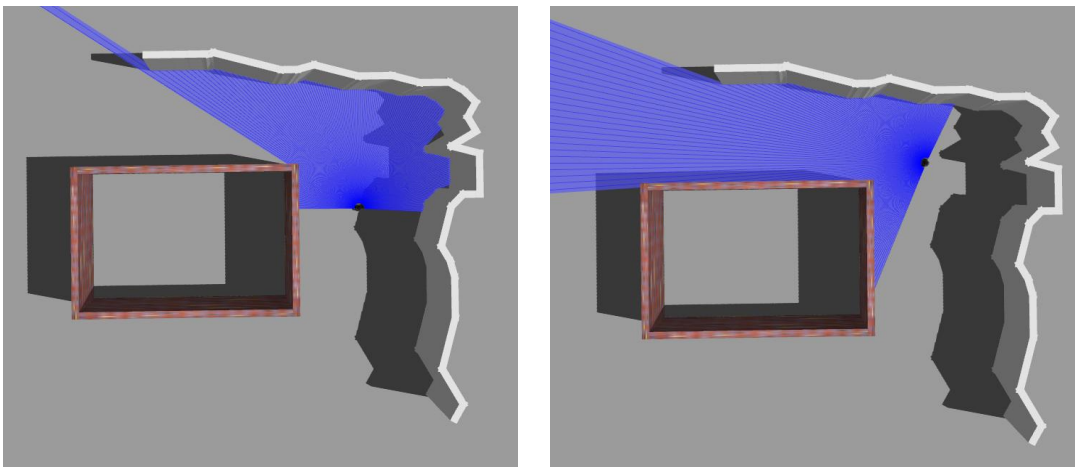
corner. And the laser point cloud lacks a reference and is prone to misalignment.



Correct example: When turning, turn sideways at a certain angle to ensure that the laser can scan the lower left corner wall and the right side contour at the same time, which can better connect the data.



4. In and out of confined spaces

After scanning a small space and exiting from the space, it is necessary to observe whether the reference objects are sufficient and whether the structural features are obvious during the scanning process. If the above two conditions are not met, when exiting, try to align the perspective with areas with good structural features as much as possible, while avoiding excessive perspective switching.

Error example: Directly turning around and exiting. This will result in missing reference objects and insufficient structural feature constraints of reference objects.

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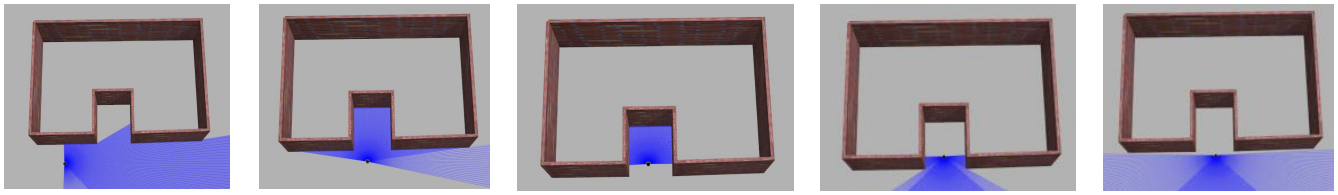
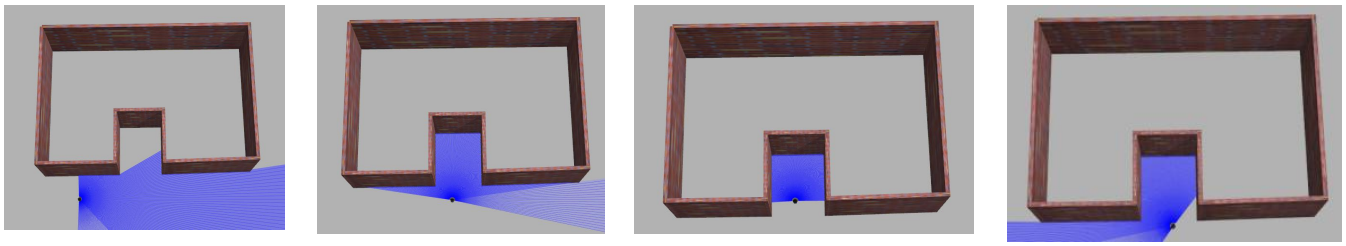


Correct example: exit by moving back or exiting sideways



8 Precautions

8.1 Startup (Instrument Initializing)

1. During initialization, it is recommended to place the device on a flat surface for static startup. Do make sure that the scanner is stable and without shaking (if possible, you can properly hold the device steady), and do not have people or obstructions in front of the LiDAR. After startup, wait for at least 10 seconds for the point cloud to appear on the phone interface. If using the latest version 1.1.0 LixelGo APP, please follow the APP prompts to initialize successfully before picking up the device. And then pick up the device for scanning. When picking it up for scanning, pick it up slowly and avoid violent movements.

2. When initialization, the collector should not block the LiDAR and stay a little bit away from the device. The LiDAR should be aimed at areas with more features, avoiding environments with fewer features such as open plains, environments with refraction such as large areas of glass, and areas with lots of dynamic objects, to ensure sufficient initialization features and obtain better data results.

8.2 General notes

1. Avoid rapid and drastic body movements or sudden stops, which may cause the

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device to deflect and swing rapidly and drastically, affecting the accuracy and effect of point cloud mapping to a certain extent.

2. When scanning, it is recommended to walk at a normal walking speed. For situations with fewer features, narrow spaces, turns, etc., it is recommended to slow down.

3. When scanning, tilt the device slightly forward about 15° to obtain a more complete field of view. In normal walking conditions, the device should not be tilted more than 20°. If you need to scan the entire ground in some narrow areas or need to scan ground targets, the device can be tilted more than 20° temporarily, but can not exceed 30°.

4. Avoid long-term obstruction of large objects within the 1m field of view of the LiDAR, and avoid obstruction exceeding 50% of the LiDAR field of view.

5. To ensure the scanning effect and accuracy, try to keep at least 0.5m away from the scanned object when scanning.

6. To ensure the scanning data results, when scanning some important ground data, try to scan at a closer distance and ensure the scanning posture: hold the scanner in the center of the body and avoid being too close to the ground.

7. For outdoor scenes such as roads and streets where there are lots of dynamic objects such as people and vehicles, be careful not to aim the LiDAR at dynamic objects when scanning. If conditions permit, if there are many dynamic objects on one side, aim the LiDAR on the other side to avoid having too many dynamic object features in the LiDAR field of view.

8. If the indoor scene involves scanning multiple rooms or floors, please open the door in advance, and scan slowly when passing through the door, and stay sideways for a while to scan to ensure that the features on both sides of the door can be scanned at the same time. If the door is not opened during scanning, turn around slowly before approaching the door, turn the instrument back to the door, open the door with your back, and enter slowly.

8.3 Ground control mode

1. When putting down the scanner to mark control points, avoid large collisions with the ground to avoid vibrations. When picking up the scanner after marking the control points, do it slowly and steadily, otherwise violent movements will affect accuracy.

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2. Mark the control point first. After the APP reports that the control point has been added successfully, pick up the scanner and walk around the control point 1-2 times or stay there for a while to obtain a more complete point cloud around the control point.

3. After marking the control point, if you want to end the project, please wait for more than 15 seconds before ending the project.

4. To ensure the accuracy of post-processing, the distance between two control points should be less than 50m and evenly distributed within the scanning area. Note: The control points cannot be on a straight line.

8.4 RTK mode

1. The RTK module can only be used when there is an RTK differential signal. And it cannot be used when there is no signal indoors.

2. Pay attention to the holding method. For the new tilt RTK bracket, under normal circumstances, ensure that the device is tilted no more than 20°. That is, the RTK antenna is vertical; the maximum tilt of the RTK antenna cannot exceed 10°.

3. In order to ensure the accuracy of post-processing point cloud conversion, pay attention to the scanning space range when scanning, and ensure that the scanning area range is more than 10m. Moreover, it is necessary to ensure that the RTK valid data is > 20 to perform coordinate conversion normally, otherwise the conversion will fail. (When using LixelStudio software to set RTK, if the valid data is less than 20, coordinate conversion will not be possible).

4. If accuracy check is needed, the acquisition route must be more than 100m and not a straight line.

5. To ensure the accuracy of point cloud post-processing, try to ensure that the RTK continuous unfixed solution is less than 50m.

8.5 Colorization mode

1. In order to ensure the colorization results, during scanning, it is necessary to ensure that the scanning duration is more than 2 minutes, and there must be movement during scanning, and the scanner should not be stationary in the same position.

2. Point cloud 's coloring effect depends on the surrounding environment and ambient

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light . For dark environments, if colorization is needed, it is recommended to light up to ensure uniform brightness around. Avoid excessive light and overexposure during the scanning process.

3. When scanning, pay attention to the way the scanner is held, and try to avoid the panoramic camera or the built-in cameras being blocked or having objects on one or both sides of the cameras for a long time, so as not to affect the coloring effect.

8.6 Accuracy Check

For accuracy check, the points where the target is pasted need to be scanned around the target or stay at the target appropriately to obtain a more complete target point cloud so as to improve the success rate of automatic target point extraction in subsequent accuracy check in LixelStudio.

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