OmniSLAM

CARVING THE REAL WORLD ACCURATELY

Mobile SLAM COLOR

3D Laser Scanner

R8 Surveying & Mapping

World-Realistic Color · Precision Level (cm)

Rotating Single Lidar

R8-Surveying & Mapping · World-Realistic Color · Precision Level (cm)

R8 is a tool that can be handheld, wearable, and vehicle-on which allows to be widely used in various fields, such as real 3D, topographic mapping, water conservancy surveys, completion surveys, traffic surveys, mine surveys, facade surveys, underground space mapping, power inspections, and forestry surveys, etc.

▲ Wearable

2cm
Repeatability Accuracy

RTK-SLAM
PPK-SLAM

0.015° Honrizontal &
Vertical Accuracy Error

Accuracy Report &
GCP Inserting Instruction

PARAMETER

Relative Accuracy[1]	1cm
Absolute Accuracy[2]	Horizontal 1.8cm, Vertical 2.5cm
5A Criteria of Surveying and Mapping[3]	√
Repeatability Accuracy[4]	2cm
Horizontal/Vertical Accuracy Error	0.015°
Point Cloud Density[5]	10,000 pts/m²
Point Cloud Thickness	1cm
Imager Sensor	1inch SONY CMOS*2
Camera Field of View	360°
Lens	Leica F2.2*2

Movable Objects Removal	√
CORS System	√
LIO-PANO[6]	√
RTK-SLAM[7]	√
PPK-SLAM[8]	√
LiRF	×
3D Real Scene Mesh Models	×
3D Thermal Map of Point Cloud Accuracy	√
Accuracy Report	√
GCP Inserting Instruction	√

MODEL

	R8-16	R8-32/300
Laser Channels	16	32
Measure Range	120m	120m/300m
Points per Second	320,000	640,000

1/2/4. Scenes with weak quantity and quality can impact Repeatability Accuracy, Relative Accuracy, and Absolute Accuracy, it's better to acquire the accurate point cloud results according to the working methods which are recommended by the manufacturer.

3. 5A Criteria of Surveying and Mapping: In the geogspatial information, anyone, at any time, using any device, following any route, and scanning any scene, can obtain the unique result of point clouds.

5. Point Cloud Density: Products can approach to the maximum density of point clouds.

6. LIO-PANO: Online colorization technology with multi-model fusion of lidar and panoramic camera.

7. RTK-SLAM: Tightly coupled complementary filtering algorithm of Real-Time Kinematic.

8. PPK-SLAM: Tightly coupled complementary filtering algorithm of Post-Processed Kinematic.

9. LiRF: Lidar Radiance Fields.

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