

# Detailed specifications

\*1 The figures are provisional and may differ from the final specifications.

\*2 PCD (.pcd): A format defined by the Point Cloud Library (PCL). Supports both text and binary.

\*3 However, the sensor temperature must be below 70°C.

Distance measurement related	
# of Dots	576 dots (288 dots with 30M30Fmode)
FOV	HFOV 35.5±2°, VFOV 28.2±2°
Ranging element	dToF SPAD distance sensor
Light source element	VCSEL Laser diodes
Wavelength	940±6nm
Accuracy	±50 mm at 10 m *1
Distance Resolution	0.25 mm

Mode	Max. Distance	Dots (H x V)	Framerate
20M	20m	24 x 24	30fps
30MSTD	30m	24 x 24	30fps
30M15F	30m	24 x 24	15fps
30M30F	30m	24 x 12	30fps
40M	40m	24 x 24	15fps

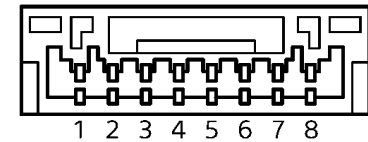
Output Date format	
Depth Data	Point Cloud Data*2 or Point Cloud Z Axis only
Intensity Image	UVC YUV2

Standards etc.	
Laser Class	Class 1 Eye Safety Class 1 IEC/EN 60825-1:2014(Ed.3)
Standard	EN55035 ClassA, FCC ClassA
Guaranteed performance temperature	0°C ~ +40°C*3
Operating Temperature	-5°C ~ +45°C
Storage Temperature	-30°C ~ +60°C
Operating humidity	20% ~ 80% (no condensation)
Storage humidity	20% ~ 80% (no condensation)
Shock resistance	200G(7~8ms)
MTBF	Approx. 10.9yrs
Supported OS	Windows11, Ubuntu24.04LTS for x64, Raspberry Pi OS 13 May 2025 (32/64-bit), Jetson Jetpack 6.2
SDK	Python
IMU	Build-in

Chassis	
Dimensions	W29 x H29 x D31 mm (excluding protrusions)
Weight	Approx. 46g (1.6 Oz)

Interface/Power Supply	
External connector	USB type C (For host connection) x1 USB type C (For daisy chain) x1 Serial8Pin GH connector(UART) x1
Power supply	USB Power or DC12 ~ 24V
Power Consumption(W)	Max. 2.5W

## 8Pin Connector



Pin	Name	Input/Output	Function
1	GND	-	Ground
2	VCC	Input	External power supply
3	Triger In	Input	Ranging start trigger pulse
4	Triger Out	Output	Ranging pulse
5	UART TX	Output	UART transmitter
6	UART RX	Input	UART receiver
7	TS Clk	Input	TimeStamp clock pulse
8	TS Preset	Input	TimeStamp value set pulse