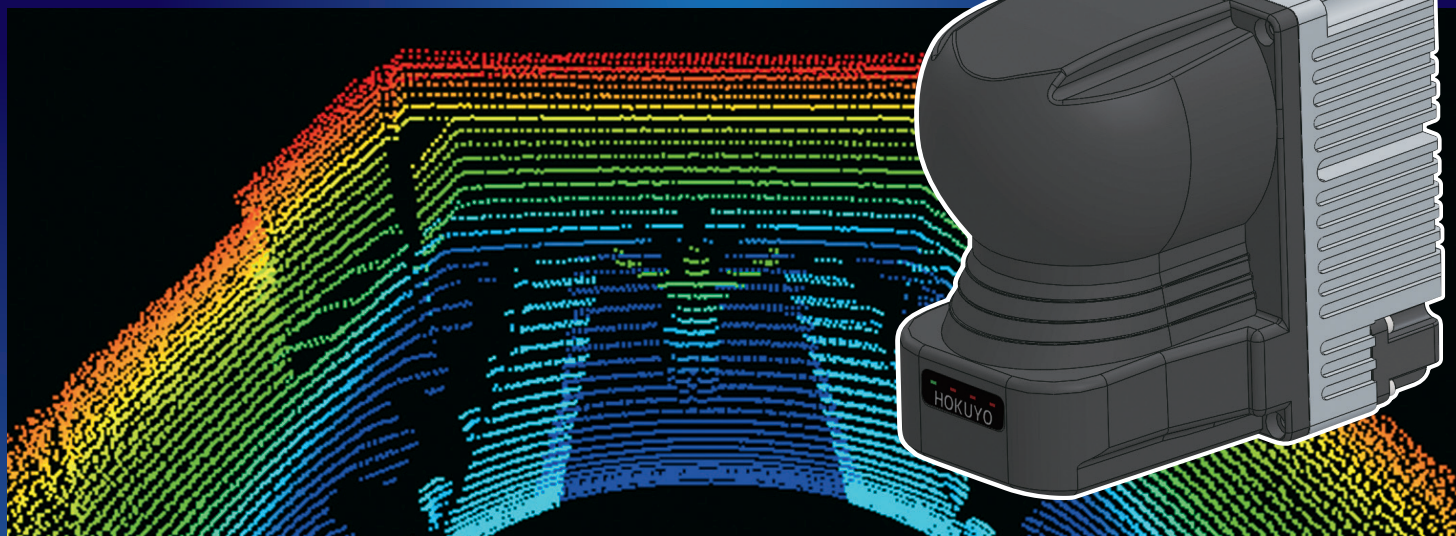


# YVT-35LX

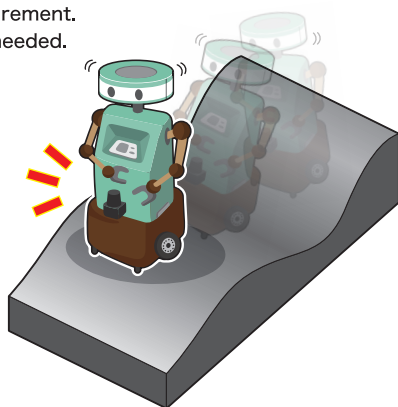
## 3D Laser scanner



- 40° vertical scanning range
- 40% increase in detection distance
- Suitable 3D solution for mobile robot

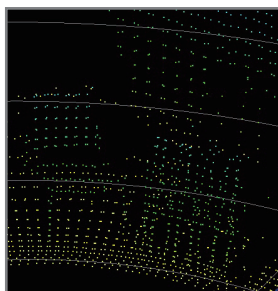
### ▶ Built-in IMU

Attitude data from IMU can be used for correction of 3D measurement. Time correction is not needed.

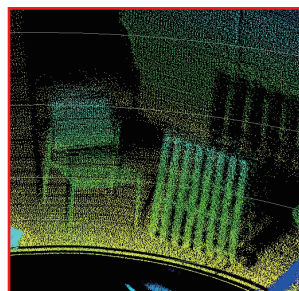


### ▶ HD (High-Density) mode added

High-density point cloud makes it easy for environment recognition



Previous Performance



HD mode

### ▶ Specifications

Model	YVT-35LX
Detection range	Front: 0.3-35m (white paper), right and left side: 0.3-14m (white paper)
Angular range	Horizontal: 210°, Vertical: 40°
Scanning speed	20Hz
Repeated accuracy	±50mm (white paper, below 15m)
Interface	Horizontal: 2-20 times HD Mode: Horizontal: 20 times, Vertical: 10 times
Data spots (Resolution)	More than 2,590 spots (None interlace, 20fps) More than 518,000 spots (Interlace HD Mode, 0.1fps)
Number of Echoes	Max.4
IMU data	Acceleration and angular velocity
Interface	Measurement data: Ethernet I/O: PPS input and scanning sync. output
Protective structure	IP67
Ambient illuminance	Sunlight below 100,000lx
Vibration resistance	10G in X, Y and Z directions
Sound level	Below 59dB
Size	70mm × 106mm × 95mm
Weight	Below 650g

Note: The specifications are subject to change without notice

### ▶ PPS (Pulse Per Second) input

When GPS is applied in a system, the PPS signal can be used to reset sensor's internal time stamp and eventually correct the accumulated error.

### ▶ Synchronous Output

This is the timing signal of the position of internal optical scanner. The signal can be used to synchronize external devices.



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