

TrueView 540

User Manual



Aerial Surveying | June 2025

Make your work more efficient.



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1 Reading Tips

1.1 Symbol Description

S Forbid

▲ Warning

Important notes

Operate & Using tips.

1.2 Disclaimer

• The customer should use and maintain the equipment in accordance with the requirements of the manual. If the service life of equipment is affected due to improper use or maintenance, even broken, GEOCUE will not bear the relevant responsibility. All repairs and maintenance services resulting from this will be charged at standard prices.

 During transportation, if the equipment is damaged due to improper logistics operation, GEOCUE will not bear the relevant responsibility.

 During equipment use, if a customer disassembles and assembles the equipment without GEOCUE's suggestions & permission, resulting in damage, GEOCUE will not bear the relevant responsibility.

Customer should use default batteries and accessories. The use of non-original accessories is not eligible for warranty; if an accident occurs, the manufacturer will not bear the corresponding responsibility.

• The M300 drone and Skyport interface mentioned in the appendix are products of DJI Innovations Co., Ltd., based in Shenzhen, China.



2 Usage Requirements

2.1 Environment

• For safety purposes: It is not recommended to use in rainy, snowy, or foggy weather. Also, the point cloud data will have more noise.

• It is not recommended to frequently use in dusty environments, which will affect the service life of equipment.

It is strongly recommended to avoid exposure of devices and accessories to extreme temperatures. The environmental temperature must not be lower or higher than the specification temperature.

When the equipment is transferred from a cold environment to a warm environment, water may condense on certain components inside the scanner. To avoid this, it is recommended to place the scanner in a sealed plastic bag before transferring. When the condensation is evaporated, then the sensor can be removed from the plastic bag.

2.2 Tips Before Using

 Check whether the laser glass is normal, if there is dust, please use the cleaning kit to clean it.

• Check whether the ports are clean and whether the pins are normal.

 Check whether the connecting cables are reliable and stable and that the GPS cable is stable and normal.

2.3 Tips During Usage

• When using, make sure that all cables and ports are connected correctly.

• After powered on, check whether the connection between remote controller and equipment is normal, and whether the status of tracking satellites and board are normal.

Place equipment in an open sky area with a good GPS signal when powered on.

 If the buzzer sounds abnormally during the capture process, please immediately check whether the equipment status is normal.

 Before starting work, check the remaining capacity of the data memory card. If the remaining capacity is less than 10% or does not meet the current collection capacity requirements, the old data file(s) needs to be deleted in advance.

• Check whether the controller's laser parameter settings are correct. If not correct, please reset it again according to the project requirements.



2.4 Tips After Using

- After using, unplug the cable first, then place the equipment into equipment case and accessories into accessory case.
- During transportation, take care of the equipment and try to avoid bumps.

3 Product Description

TrueView 540 is a new generation of mid-range airborne LiDAR system launched by GEOCUE in partnership with CHCNAV. Based on the design concept of "strong penetration, high precision", the TrueView 540 integrates high-performance LiDAR, high-precision inertial navigation and a full-frame camera. Sensor data download and processing are performed with LP360 processing software. This provides "high precision, high efficiency, and low cost" 3D data acquisition and complete processing solutions for customers in terrain surveying, engineering surveying, power line inspection and other industries.

♂ 3.1 Hardware Check List

Note: Please refer to the actual delivery list.

TV540 LiDAR system configuration list is shown below:

	Description	Model	Pcs
1	TV540 unit	TV540	1
2	TV540 transport container		1
3	USB3.0 to TYPE-C adapter cable		1
4	USB disk (32G)		1
5	Lens cleaning wipes		10
6	Lens cleaning air blower		1
7	Mount platform for M300 or TrueView Payload Adapter		1



3.2 Delivery of Equipment and Materials

Note: Please refer to the actual delivery list.



GNSS antenna 1.

3.

2. TrueView 540 LiDAR system

Lens cleaning air blower

- 5. Mount adapter
- 6. USB drive 1
- 7. USB drive 2
- Shock absorbing dampeners for M300/M350 4.
- 8. Supporting documentation



TrueView 540 LiDAR system:



TrueView 540 transport container:





Mount adapter and GNSS antenna:



Lens cleaning air blower and cleaning wipes:





3.3 Physical Characteristics

3.3.1 Weight and Size

- Weight: 1.55kg.
- Length, width, and height (210×112×131mm):



3.3.2 Interface Definition



- 1. USB Type-C port for data copy.
- 2. LED indicator for device status.



LED indicator & buzzer	Device status
LED Indicator off	Power off
Quickly blink (5 times per second)	Under initialization
Solid	Initialization successful
Slowly blink (2 times per second)	Create project successfully;
	GNSS & IMU data collecting
Normal blink (1 time per 2 second)	Data capturing
Abnormal blink with sound	Abnormal status

3.4 Power Supply and Physical Characteristics

Power consumption	40W		
Working temperature	-20 °C to +50 °C		
Storage temperature	-20 °C to +60 °C		



3.5 TV540 Technical Data

3.5.1 Laser Product Classification

Class 1 Laser Product according to IEC 60825-1:2014



3.5.2 Max. Measuring Range

Laser Pulse Repetition Rate PRR	100kHz	300kHz	500kHz
Max. range, @ρ >10%	283m	194m	152m
Max. range, @ρ >20%	400m	275m	215m
Max. range, @ρ >80%	800m	480m	280m

NOTE:

- Rounded values.
- Flat terrain assumed.
- Typical values for average conditions. Maximum range is specified for flat targets with size more than the laser beam diameter, perpendicular angle of incidence.

3.5.3 Max. Operating Flight Altitude AGL

Flat terrain assumed, scan angle 75° (± 38°) FOV

Laser Pulse Repetition Rate PRR	100kHz	300kHz	500kHz
@ρ >10%	224m	154m	121m
@ρ >20%	317m	218m	170m
@ρ >40%	449m	308m	222m
@ρ >60%	549m	378m	222m
@ρ >80%	634m	381m	222m

NOTE:

- Rounded values.
- Flat terrain assumed.
- Different target reflectance has different max. operating flight altitude AGL.

(1) When the mission area consists of post-rain scenes or mainly targets of asphalt materials, which have low reflectance, it is recommended to set the flight altitude with a reflectance $\rho > 10\%$.

(2) When the mission area mainly composed of materials like deserts, limestone, etc., it is recommended to set the flight altitude with a reflectance $\rho >40\%$.

(3) For other general mission areas, it is recommended to set the flight altitude with a reflectance ρ >20%.

3.5.4 Max. Operating Flight Altitude AGL & Point Density

The graph below shows the maximum operating flight altitude AGL at different Laser Pulse Repetition Rate PRR under different target reflectance.

The graph below also shows the relationship between the average point density within a single strip and the flight speed.











4 Installation And Disassembly Guide

4.1 Installation Steps

Push the "Alphaport" slider of scanner into the quick-release clamp which is on the bottom of the airborne mounting platform in the direction of the arrow until the user hears a "click" sound.

- Tighten the side screw bolt to make it stable to complete the installation.
- Insert the rod antenna into the antenna mount and tighten it.



4.2 Disassembly Steps

- Unscrew rod antenna and remove.
- When removing the TV540 from the platform, hold the bottom of device with left hand, loosen the side screw bolt counterclockwise with right hand until the threaded part of the side screw bolt disengages.

Pull the side screw bolt back to the maximum position with the right hand and keep the bolt in this position. Pull the "Alphaport" slider of scanner out the quick-release clamp which is on the bottom of the airborne mounting platform in the direction of the arrow.





5 Product Usage

5.1 Advance Preparation

- Check the equipment to ensure that the contents and other accessories are not missing.
- Check whether there are any stains on the laser beam exit window and camera lens. If there are stains, use the cleaning tools provided with the package to gently wipe and clean them.
- Make sure the batteries of the base station, aircraft, and remote control are fully charged.
- Using the remote, check sensor authorization and storage space.
- Confirm whether there are tall buildings or interference sources near the take-off point.

5.2 Flight Planning

For flight planning, use the sensor Web UI to calculate flight line spacing and set the camera trigger interval and camera parameters. Enter the desired altitude, speed, sidelap and front lap and tap the Apply button. The required flight line spacing will be shown at the bottom of the screen. 80% frontlap is sufficient for most general applications, sidelap should be a minimum of 40%. The range of the sensor is dependent upon the settings used but generally exceeds the FAA altitude limit for sUAS. The practical range is 400m at >20% reflectivity.

Box Turns

At the end of each flight line, the drone will change headings and transition to the next flight line. To optimize accuracy, it's recommended to perform box-turns at the ends of flight lines. These are highly efficient turns that also keep the heading aligned. Some flight planning applications attempt to create rounded turns to avoid stopping and save time, but box-turns are better for IMU output. A box turn can be described as follows:

- At the end of a flight line quickly coming to a hover
- Rotate about the Down axis by +/-90 deg
- Accelerate to the start of the next line and come to a hover
- Rotate about the Down axis by +/- 90
- Accelerate and fly the next line

5.3 Equipment Installation

Take out the equipment from the container before using. Install on the corresponding platform, lock by tightening screw and connect all cables. For detailed information, refer to Section 4.1 and for DJI M300/M350 – Section 11.2



5.4 LiDAR Power On

Set up the base station in an open sky area with recording frequency set at 1Hz (1 observation per second). Turn on the equipment after the base station starts recording static data.

GNSS Base Station Requirements:

- L1/L2 Support
- At minimum: GPS and GLONASS constellations observed
- RINEX Export (V2.11 or later.)
- Coordinates of observation in Lat/Long/Elevation (Ellipsoid (m))
- Input reference frame used for the base location (ETRS89/NAD83(2011)/ITRS2014/WGS84)
- Antenna Height
- Antenna Height measurement type
- Manufacturer Model
- 1Hz interval

• The base station should be recording 15 minutes before the flight and 15 minutes additionally after landing.

 Baseline length: The base station should be the closest possible to the flight area with a maximum distance not greater than 20 km.

• Wait for about ten seconds for the device's indicator light to start flashing. This means the system has powered on successfully and started initializing.

Use phone or tablet to search for the WIFI of TV540 and connect to the device. For detailed information, refer to <u>Chapter 6</u>.

After powering on the TV540, wait around 1 minute until the device indicator light becomes steady on, indicating that the device initialization is complete.

Note: The correct procedure is to install the TV540 first and then power on the aircraft. The TV540 does not have an on/off switch; the TV540 will automatically power on when the aircraft is powered on. So, please make sure to install the TV540 before powering on the aircraft.

5.4 Data Collection

 After power up, to begin data collection, the sensor needs to sit on the ground for 3 mins before takeoff to collect a brief static observation which is needed for trajectory processing.
 When the static collection is complete the sensor will beep to indicate it is ready to fly.

The sensor has a proximity zone feature that will begin (assuming that the user is utilizing Auto mode) and end based upon altitude and vibration. This can be changed to manual start/stop within the WebUI, but it is recommended to use proximity (Auto) mode.

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Because the DJI M300/M350 integration makes the aircraft front heavy, it is recommended to take off briskly, a slow take-off could potentially cause rocking and damage the sensor or aircraft. Once the aircraft is in the air and stable, perform a center of gravity calibration through DJI Pilot in a wind free environment to ensure the aircraft is balanced with the payload. Additional Center of Gravity Instructions for DJI Platforms:

- Launch the DJI Pilot application, open a mission, or go into the manual view.
- Tap the Ellipsis menu (...) on the top right corner of the screen.
- Stay within the Flight Controller Settings tab and scroll to the bottom of this screen.
- Tap the Center of Gravity Auto Calibration Button and follow the instructions.

The heading alignment calibration should be a single figure eight maneuver at around 5 m/s (11mph) before the flight plan is executed and prior to landing.

•The data streams are written in real time to the sensor's internal 1 TB storage drive so no waiting is needed. Once the aircraft lands, allow it to collect static data again for 3 minutes until a beep is heard. The sensor is then ready to power cycle with the aircraft for more flights.

Basic flight operations overview/summary:

- 1. Set up the sensor on the drone.
- 2. Power on the drone.
- 3. Wait 3 minutes while the TV540 initializes, you will hear a beep once it is ready.
- 4. Take off.
- 5. Perform heading alignment maneuver, with figure-8 pattern at 5m/s.
- 6. Start the mission.
- 7. Finish the mission.
- 8. Perform the head alignment maneuver again (figure eight).

9. Land.

- 10. Wait 3 minutes for the sensor to wind down. You will hear a beep once it finishes.
- 11. Power off the drone.

5.6 LiDAR Power Off

- Before powering off equipment, please make sure the project recording has stopped.
- Turn off the power supply of the drone platform to power off the equipment.

TV540 has no "ON/OFF" button, which will be powered off automatically after the drone platform power supply has been turned off.



6 Product Workflow

TrueView 540 uses a webpage-based user interface to configure settings and control. The webpage can be accessed from any computer, tablet, or mobile browser.

6.1 TV540 Connection

After TV540 installation is completed, turn on the drone's power. The TV540 will power on automatically, wait for about ten seconds, and the device's indicator light will start flashing, which means the system has powered on successfully and started initialization.

TV540 WiFi will be available which is named "TV540-xxxxx" (where "xxxxx" represents the last five digits of the device's serial number). Once connected to the device, scan the QR code located in the middle of the TV540 device box (see the figure below). It will login to the control web page of TV540. Users can also enter the web address "192.168.100.100" in the mobile phone's (also laptop or tablet) browser to access the control interface of TV540.



Note: When connecting to the device using the mobile phone's Wi-Fi function, if the webpage is not allowed to access, 4G or 5G data mobile data connection may need to be disabled.

After powering on the TV540, wait around 3 minutes until the device indicator light becomes solid green, which means the device initialization is complete.

Note: The correct procedure is to install the TV540 first and then power on the aircraft. The TV540 does not have an on/off switch; the TV540 will automatically power on when the aircraft is powered on. So, please make sure to install the TV540 before powering on the aircraft.

WebUI Access via Corporate/Secured Networks

If you're attempting to access the TrueView 540 web UI from a device that is also connected to a corporate or secured network (e.g., via Ethernet or VPN), the following considerations apply:

- Local IP Access: The TV540 is accessed at 192.168.100.100. Ensure your firewall allows outbound HTTP traffic (port 80) to this IP.
- **Disable Mobile Data**: On mobile devices, disable 4G/5G to avoid routing conflicts that may block access to the local IP.
- Wi-Fi Isolation: Some enterprise Wi-Fi networks block peer-to-peer connections. Ensure your device is connected directly to the TV540's Wi-Fi (TrueView540-xxxxx) and not to a guest or corporate network.

Suggested Firewall Exceptions (if needed)

If you're working in a restricted IT environment and need to request firewall exceptions, here are the likely settings to whitelist:

Setting	Value			
Destination IP	192.168.100.100			
Port	80 (HTTP)			
Protocol	ТСР			
Direction	Outbound from client device			

Additional Troubleshooting

If you're still having trouble:

- Try accessing the web UI from a different device (e.g., a tablet or laptop).
- Clear your browser cache or try a different browser.
- Ensure the TV540 is fully initialized (solid green light) before attempting access.



6.2 TV540 Webpage Configuration

Please refer to the software interface.

The webpage interface is displayed as follows:

	TRUEVIEW 540					
	Settings	Parameters				
1	Status	Mode		Camera Trigger M	lode	
)	About	MANUAL	AUTO	TIMER	EXT	NONE
		AGL		Flight Speed		
	CLOSE PROJECT	100	m	5.0		m/s
		Image Heading Overlap		Image Side Overla	ip.	
	START COLLECT	60	%	45		%
		Configuration				\$ APPLY
		Pulse Repetition Rate		Line Speed		
		100K 300K	500K	210		l/s
		Max ISO		Max Shutter Time		
		3200	-	1/800		s 🕶
		Development				
		Preview				
		Flight Spacing	Ped Strip Width		Pod Overlap	
		94.3 M	100.7 m		39.4 %	
		Average Pcd Density of Strip 535 p/m ²	Nadir Pod Spacin 5.3 cm	g	Line Spacing 2.4 cm	
		Image Strip Width 171.4 m	Image Heading 0 60.2 %	verlap	Image Side Over 45.0 %	lap
		Image GSD 2.1 cm	Trigger Interval 9.1 s (45.5m)			

Manual mode interface

	TRUEVIEW 540						
¢	Settings	Parameters					
11	Status	Mode		Camera	a Trigger Mo	de	
Ð	About	MANUAL	AUTO	т	IMER	EXT	NONE
		AGL		Flight S	speed		
		100	m	5.0			m/s
		Image Heading Overlap		Image S	Side Overlap		
		60	%	45			%
		Configuration					APPLY
		Pulse Repetition Rate		Line Sp	reed		
		100K 300K	500K	250			l/s
		Max ISO		Max Sh	utter Time		
		3200	-	1/80	0		s -
		Preview					
		Flight Spacing	Pod Strip Width			Pcd Overlap	
		94.3 m	155.7 m			39.4 %	
		Average Pcd Density of Strip	Nadir Pcd Spacin	g		Line Spacing	
		535 p/m ²	5.3 cm			2.4 cm	
		Image Strip Width	Image Heading O	verlap		Image Side Overla	p
		171.4 m	60.2 %			45.0 %	
		Image GSD	Trigger Interval				
		2.1011	9.15 (40.011)				
		I					

Auto mode interface

The operation mode of TV540 has two options: Manual mode and Auto mode. Users can switch between "manual" and "auto" modes.

6.2.1 Recommended Flight Parameters

Sensor power is provided through integration kit, the sensor does not have a dedicated power switch but is instead turned on and off when the aircraft is powered. The sensor does not have a built-in battery compartment. Once the integration kit is installed and the aircraft is powered on the sensor can be monitored and settings altered through the sensor's Web UI. To connect to the Web UI, use a phone, tablet, or computer to connect to the sensors Wi-Fi, no password is needed. Then open a web browser and go to the address 192.168.100.100. Refer to Section 6.1.

- 1. Set up the sensor with the drone platform.
- 2. Switch on the drone.
- 3. The sensor will switch on automatically, wait 3 minutes while the sensor initializes.
- 4. The sensor will beep once is ready to fly.
- 5. Connect to the sensor Wi-Fi, network (Example: TRUEVIEW540-0000F).
- 6. Access to the web UI, site 192.168.100.100.
- 7. Select (Example of recommended common parameters):
 - 1. Parameters
 - A. Mode \rightarrow AUTO
 - B. Camera trigger mode \rightarrow TIMER.
 - C. AGL \rightarrow input desired height.
 - D. Flight Speed \rightarrow 5 m/s.
 - E. Image Heading Overlap \rightarrow 80%.
 - F. Image Side Overlap \rightarrow 40%.
 - 2. Configuration
 - A. Pulse Repetition Rate \rightarrow 500K.
 - B. Line Speed \rightarrow 250 m/s.
 - C. MAX ISO \rightarrow 3200.
 - D. Max Shutter Time \rightarrow 1/500s.
 - E. Click \rightarrow APPLY.

6.2.1 Manual Mode

The default setting is manual operation mode. However, this is not the recommended mode. We recommend switching to AUTO Mode. Please refer to the <u>AUTO Mode (proximity mode)</u> <u>section</u>. In case the manual mode is still needed, the specific workflow is as follows:

1. Configure the "Camera Trigger" option first. There are three camera trigger modes: TIMER, EXT and NONE. The default operation mode is "TIMER". This setting is recommended as the external signal trigger is not supported in this product version integration.

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Available Camera Trigger Modes and Related Settings:

- > Timer: Camera takes pictures by time interval. The minimum interval is set to 1s.
- Trigger param (s) = (1-camera heading overlap) * GSD (m) * 5460/flight speed (m/s).
- GSD (m) = AGL (m) * pixel size (mm) / focal length (mm).
- External: Camera takes pictures by external signal trigger.
- None (Disabled): Camera will not take pictures.

Parameters						
Mode			Car	mera Trigger M	ode	
	MANUAL	AUTO		TIMER	EXT	NONE

2. When the camera is enabled, the user needs to input AGL, flight speed, image heading overlap and side overlap in relation to project conditions and data requirements. When the camera is disabled, the user will only need to input AGL and flight speed information.

3. After the parameter settings are completed, in the "Configuration" section, the software automatically calculates and sets the recommended pulse repetition rate and line speed based on input parameters such as AGL and flight speed.

4. After clicking "Apply", the settings of pulse repetition rate and line speed will be implemented.

AGL			Flight Speed	
100		m	5.0	m/s
Image Heading O	verlap		Image Side Overlap	
60		%	45	%
Configuration				APPLY 🗘
Pulse Repetition	Rate		Line Speed	
100K	300K	500K	250	l/s

Ē

Note: When there is strong wind, the flight attitude of the drone may become unstable, resulting in different laser scanning lines in each strip. In this case, the user can manually adjust the line speed to a value higher than the recommended value to achieve a more uniform point cloud. Users can also modify the pulse repetition rate and line speed according to the specific conditions of the project. The line speed can be set within the range of 50-250 l/s.



5. When the camera is enabled, set "Max ISO" and "Max Shutter" in the "Configuration" section. ISO and shutter speed will automatically adjust within their set maximum range based on the brightness of the scene.

Configuration				APPLY
Pulse Repetition Rate			Line Speed	
100K	300K	500K	250	l/s
Max ISO			Max Shutter Time	
3200		•	1/800	S 🔻

Note: Mounting on rotor-wing UAV: set "Max ISO" to 3200 and "Max Shutter" to 1/800.

Mounting on Fixed-wing UAV: set "Max ISO" to 3200 and "Max Shutter" to 1/1000.

6. After configuring the relevant parameters, in the "Preview" section, you can view the following details:

Preview

Flight Spacing	Pcd Strip Width	Pcd Overlap
94.3 m	155.7 m	39.4 %
Average Pcd Density of Strip	Nadir Pcd Spacing	Line Spacing
535 p/m ²	6.3 cm	2.0 cm
Image Strip Width	Image Heading Overlap	Image Side Overlap
171.4 m	60.2 %	45.0 %
Image GSD 2.1 cm	Trigger Interval 9.1 s (45.5m)	

7. Once the parameter settings are completed, click on "New Project". The indicator light on the device will change from a solid green to slowly blink for IMU static alignment. Do not move the drone platform/sensor for at least 3 minutes during the slow blink status.



1EW 540
ettings GNSS
atus Satellites Num Longitude
About 28 -86'4421.630"
Height Latitude 169.67 m 34/32/57,932'
CLOSE PROJECT
START COLLECT Status NEW PROJECT CREATED Details
Project Time Collecting Time
0:15:19 0:00:00
Images Missed Images 0 0
Remainless of Pard Pard Persisting of Image Card
469 GB 472 GB
Parameters
Pulse Repetition Rate Line Speed
500 kHz 250 Vs
Max ISO Mas Shutter Time 400 1/500 s
Camera Trioger Mode
TIMER (3.4 s)

8. After 3 minutes of slow blink, click on "Start Collect", the indicator light on the device will change to quickly blink, which means TV540 starts capture data. After that, the user can control UAV to take off and start mission.

9. After completing a single flight mission, the UAV will return and land. Connect to TV540 Wi-Fi and login to webpage. Click on "Stop Collect" to stop data capture. The indicator light will change to slowly blink again. Do not move the drone platform/sensor for at least 3 minutes during the slow blink status.

=					
‡	Settings Status About	GNSS Satellites Num 28 Height 122 Stra	Longtude -86°44'21.647" Latitude 34°3457'901"		
	CLOSE PROJECT	Status collection started Project Time 0/21/11 Stop Collection?	Collecting Time 0.06-32	Details	
		To stop collection is to stop scenning and photo the acquisition of point clouds and photos. Pulse Reputition Rate 500 HHz	ographing, which includes discontinuing OK CANCEL Line speed 220 V s		
		Maa IBO 3200 Camera Trigger Mode TIMER (3.1 s)	Max Shufter Time 1/980 S		

10. After 3 minutes static observation, click on "Close Project", and the indicator light will change to solid green, which means project stop & save successfully.



≡	TRUEVIEW 540					x 0
\$	Settings		GNSS			
	Status		Satellites Num 28	Longitude -86°44'21.642"		
	CLOSE PROJECT		Height 172.10 m	Latitude 34*34'57.901*		
	START COLLECT		Status NEW PROJECT CREATED		Details	
			Project Time	Collecting Time		
			Close Project?			
		1	To close the project means to stop recording trajectory	data, including IMU and GNSS		
			raw data. A static alignment is typically required for 3 r project.	ninutes prior to closing the		
				OK CANCEL		
			Pulse Repetition Rate 500 kHz	Line Speed 220 l/s		
			Max ISO 3200	Max Shutter Time 1/800 s		
			Camera Trigger Mode TIMER (3.1 s)			

11. Turn off the power of the UAV and the device will automatically shut down.

Note: The device supports saving configuration parameters. After power off and restart, the default settings will be the same as the last configured parameters.

6.2.2 AUTO Mode

TV540 also supports AUTO mode which allows automatic flight collection start and stop. This is the recommended mode for data collection. The workflow is as follows:

Steps:

1. Click on the "AUTO" button to switch to automatic operation mode.

p	Parameters					
Status	Mode		Camera Trigger M	ode		
bout	MANUAL	AUTO	TIMER	EXT	NONE	
	AGL		Flight Speed			
	100	m	5.0		m/s	
	Image Heading Overlap		Image Side Overla	p		
	60	%	45		%	
	Configuration				T APPLY	ר
	comgulation					
	Pulse Repetition Rate		Line Speed			.
	100K 300F	500K	250		l/s	
	Max ISO		Max Shutter Time			
	3200	-	1/800		s 🕶	
	Preview					
	Flight Spacing	Pcd Strip Width		Pcd Overlap		
	94.3 m	155.7 m		39.4 %		
	Average Pcd Density of Strip	Nadir Pcd Spacin	g	Line Spacing		
	535 p/m²	6.3 cm		2.0 cm		
	Image Strip Width	Image Heading 0	verlap	Image Side Ove	erlap	_
	171.4 m	6U.2 %		45.0 %		_
	Image GSD	Trigger Interval				
	2.1 cm	9.15 (45.50)				

Note: After switching to "AUTO" mode, the "New/Close Project" and "Start/Stop Collect" buttons will disappear.





2. After the device initialization is complete, a new project will automatically be created. At this time, the indicator light on the device will change from a solid green to slowly blinking.

3. Regarding parameter settings, the method for setting parameters in automatic mode is the same as in manual mode (reviewed in the previous <u>Section 6.2.1</u>). After 3 minutes of static observation (leaving drone platform stationary on the ground), the TV540 buzzer beeps for 1 second, indicating that the user can perform the aerial surveying mission.

4. During takeoff, the TV540 sensor automatically starts data collection by detecting its own vibration status. At this time, the indicator light of the device will quickly start blinking.

5. After completing a single flight mission, the UAV will return and land. The device automatically stops data collection by detecting its own vibration status when static for more than 5 seconds. At this point, the indicator light of the device changes to slow blink. Keep the drone stationary on the ground for another 3 minutes for IMU static alignment.

6. After 3 minutes, the TV540 buzzer beeps for 1 second, indicating that the user can power off the device.

7. If multiple missions need to be performed at the same takeoff point, and the drone supports hot swapping of batteries without power interruption, user can directly perform the next mission after replacing the drone battery. In this case, when the device detects vibration, it will automatically start data collection for the next mission.





Note: After data collection is completed in "AUTO" mode, you can also manually switch to the "Manual" mode to close the project.

6.3 LiDAR Status Check

Users can check TV540 LiDAR status on the webpage: GNSS, status, and parameters. Click the icon on the top-left corner of the webpage and then click the "Status" button to switch to the status check interface for viewing.

GNSS Interface: This section displays the number of satellites and positioning information.

Status Interface: This section displays the project details.

- \geq Project Time: The total time from initial project creation.
- \geq Collect Time: The total time of data captured.
- \geq Images: Total captured photos number.
- \geq Missed Images: The number of photos missed during the data collection.
- > Remaining of Pcd Card: Available storage space on the point cloud storage card.
- > Remaining of Image Card: Available storage space on the image storage card.

Parameters Interface - This section displays the project parameters:

- \geq Pulse Repetition Rate: The project used PRR settings.
- \geq Scan Speed: The project used scan speed.
- \geq Max ISO: The maximum ISO value set for the camera.
- Max Shutter: The maximum shutter for the camera. \geq
- \triangleright Camera Trigger: The time interval for the camera pictures.



Users can easily access and view this information by clicking the "Status" button after clicking the icon on the top-left corner of the webpage.

≡	TRUEVIEW 540			× 🕚
۵	Settings	GNSS		
1	Status About	Satellites Num 28	Longitude -86*44'21.640*	
	CLOSE PROJECT	Height 169.72 m	Latitude 34*34'57.876*	
	START COLLECT	Status NEW PROJECT CREATED		Details
		Project Time 0:31:45	Collecting Time 0:00:00	
		Images O	Missed images 0	
		Remaining of Pcd Card 476 GB	Remaining of Image Card 476 GB	
		Parameters		
		Pulse Repetition Rate 500 kHz	Line Speed 220 I/s	
		Max ISO 3200	Max Shutter Time 1/800 s	
		Camera Trigger Mode TIMER (3.1 s)		

Click "Details" will display the current status of "System", "GNSS", "LiDAR", "IMU" and "Camera".

=							
\$	Settings	GNSS					
	Status	Satellites Num		Longitude			
0	About	28		-86*44'21.630*			
		Height		Latitude			
	CLOSE PROJECT	104.41 m		34-34-37.000			
	START ODLLEOT	Status NEW PROJECT CREATED				Details	
		Details		×			
		Ø System	ок				
		@ GNSS	ок				
		Ø LIDAR	OK		age Card		
		Ø IMU	OK				
		⊘ Camera	OK				
			DIAGNOSIS	CLOSE			
		500 KHZ		220.1/5			
		Max ISO 3200		Max Shutter Time	÷		
		5200		11000 0			
		Camera Trigger Mode					
		(IMER (0.1 S)					

6.4 Log Download

When the device encounters an abnormal situation, it will be displayed in red on the software interface. In the "Details" section, user can view the reason for the abnormality, which will be indicated by a red exclamation mark (!) as a warning sign.

If the TV540 unit cannot be operated properly, user can download a diagnostic report from the "Details" section and send it to the GeoCue support team for analysis. Here are the steps to download the diagnostic report:

- 1. Go to the "Details" section of the software interface.
- 2. Click on the "Diagnosis" option.
- 3. Select the desired date for which you want to generate the diagnostic report.
- 4. Click on the "Download" button.

📗 report-20230519.1.zip

6.5 Authorization

The "About" interface displays the device's Serial Number (SN), Part Number (PN), Firmware Version Number, and the expiration date of the authorization. If the LiDAR expired, please contact the GeoCue support team.

≡	TRUEVIEW 540			🛪 🔮
۵	Settings	Device Info		
Ξ.	Status	SN	PN	
()	About	124110200004	S20410076624204001	
	CLOSE PROJECT	Firmware Version 1.0.24	Authorization Expired Date 2037-11-27 AUTH	
	START COLLECT	Based on open source software		
		0 1014 000000		



6.6 Firmware Update

Firmware can be acquired through GeoCue Support. Prepare the TV540 for update by performing the following steps:

1. Download the firmware (contact GeoCue support for the latest firmware download).

2. Connect the sensor via the supplied USB-A to USB-C cable.

3. In File Explorer, copy the firmware update file (Example:

"update_aa10_v1.1.0_b20240607.bin") to the sensor disk drive: "ALPHA_SYS".

4. Mount the sensor to the drone

5. Power on the drone.

6. The sensor will take 15 minutes to install the firmware update. During that time, the light will blink 5 times per second. It will beep once after it finishes.

7. Power down the drone.

8. Switch on the sensor--> Web UI--> Check the firmware version to confirm successful firmware update.

7 Data Copy Steps

Connect the TV540 to the computer with the type-C cable, the computer will pop up two disks: ALPHA_SYS contains laser data, GNSS & IMU data, and ALPHA_CAM contains picture data.

ALPHA_SYS	S (F:)		ALPHA_CA	AM (E:)	
457 GB	,	476 GB	458 GB	,	476 GB	

Note: Connect the TV540 to the computer with the type-C cable when the device is powered off. Otherwise, the SD card (data storage card) cannot be recognized.



7.1 Disk Structure



ALPHA_SYS: Both laser & GNSS & IMU data are recognized based on capture date. For example: "20210820" means the data was collected on August 20, 2021.

xxxxxx.ltp: Laser data.

xxxxxx_l.imr: IMU data.

xxxxxx_S.cil: Synchronizes data.

xxxxxx_T.gps/ xxxxxx_T.hcn: GNSS data.

*.EPX: Laser calibration file.

*.CPX: Camera calibration file.

ALPHA_CAM: Store picture data.

Note:

1. *. EPX & *. CPX: Default calibration files which cannot be modified or deleted.

2. Please do not delete or manually format disks, otherwise it will affect data copy. Users can find a backup parameter folder on USB disk if the disk folder has been deleted.



7.2 Data Copy Tool from LP360

Users need the TV540 data copy tool from LP360 software to automatically copy raw data from the device to PC: <u>LP360 Drone Users Guide – TV540 Data Copy Link</u>

Steps:

Connect the TV540 to a computer with the type-C cable and 2 disks will populate: ALPHA_SYS and ALPHA_CAM.



Click "Tools - Data Copy":

Project	Sensor Map Control Points	Point Tasks QA/QC	Classification	Feature Edit Cloud Suppo	rt			^			(LP360) [12,265.7
Ð	Active Cycle: C240321_191040 *	, , ,	° 🕹	EXIF tags/EO	Trajectory Report	7	÷. *	۲		•		
Cycle Import Import	G Update Utility	Trajectory Auto Create Processing Flight Lines	Create TV Geocoding Trajectory Cycle Processing	Adjustment Export Photo Pack	age 🖞 Pilot Log File	Post Processing	Strip Ortho Align Mappin Processing	Agisoft Ortho g Mapping	Feature K Edit N	Archive Utilitie Aanager + Archive	IS Job Manager Job	-
0 0	🕄 📵 🕐 🌑 🚔 🖛 🏓 🛛 Active Las Layer:		* ige Filter:	- 💙 🕅 E	levation * 📓 Points.* 🕯	Contours - K	a 16 🛛	R 🕼 🖬 🛆 -	- Pi	~	The state of the s	
lable Of Co	ontents - LP360	a × pile / service	-1-2 × 1.	3D Window - L	.P360			# >	Survey	Nail Calibration	Live DJI PF	TV540
~ # M	ap (All Layers)		1	haar Kalifa y 🦲 - 💹	- II 📴 👯 🌆	. 🖸 🖻	Т 🌀	入口 🖻	1 Manag	ger	Stream Utilit	Data Co

• Choose the correct device from "Module1" list, then select projects from left list and click "Settings".

Finally, click "Finish".





• The data copy tool will read LiDAR type and SN on left top corner.

🗐 Data Copy							_ >
Type AA10 SN 124110200004 Carrier UAV_M300	SYSTE	M 476.58GB is available	LIDAR 476.58GB	is available	CAMERA Stored: 17,can	476.60GB is availal	ble CReload
Project	Camera	Scanner POS					
Select All	ID	File Name	File Size	Mod	lification Date	File Descrip	otion
@@2024-07-22-104733	1	20240722_170557_000.ltp	47.00KB	2024.07	.22 17:06:53	Scanner_LT	
	Output: C:/Users/jackson.dalby/Desktop/TrueViewData/TV540/132SN023						Сору
		100%	Match project data finishe	ea.			

Picture number: 17 Collect time(min): 29.2 Missing picture number: 0 Missing POS number: 0



• Users can check project data folders of the device in the data column on the left. Select one or multiple sets of data, then it will display corresponding camera pictures, laser, and GPS data on the right side.





Picture number: 17 Collect time(min): 29.2 Missing picture number: 0 Missing POS number: 0



ype any su	SYSTE	M 476.58GB is available LID.	AR 476.58GB i	s available CAMERA	476.60GB is available	📿 Rel
N 124110200004				Charadi 17 ann a	tore: 170606	🗲 For
arrier UAV_M300 =				Stored, 17,can s	lore. 170020	🔁 USE
ject	Camera	Scanner POS				
Select All	ID	File Name	File Size	Modification Date	File Description	
@@2024-07-22-164733	1	20240722_164733_S.cil	165.00KB	2024.07.22 17:16:50	Camera Trigger Data	
	1	20240722_164733_D.dmr	27.00KB	2024.07.22 17:16:50	Encoder Data	
	1	20240722_164733_l.imr	26.79MB	2024.07.22 17:16:50	Inertial Sensor Data	
	1	20240722_164733_T.gps	21.36MB	2024.07.22 17:16:50	Mobile Station Data	
	1	20240722_164733_T.hcn	21.37MB	2024.07.22 17:16:50	Mobile Station Data	

Note: Select one or multiple sets of data needed to copy with Ctrl and Shift shortcuts.
 Note: Double-click on a photo to view details.





Define an output path to store project data.



Picture number: 148 Collect time(min): 10.9 Missing picture number: 0 Missing POS number: 0

Click "Copy" and it will automatically copy selected data projects.

Data Copy					1
Туре не.	SYSTEM 476.58GB is	s available LIDAR	476.58GB is available	CAMERA 476.60GB	is available C Reloa
SN 124110200004				Stored: 17,can store: 170	626
Carrier UAV_M300 *					🔁 USB I
Project	Camera Scanner PC)S			
@@2024-07-22-164733	NE C	NE (NE (NEG	NE
	SEAG000001	SEAG000002	SEAG000003	SEAG000004	SEAG000005
	NEA	NE (NEC	I	NE (
	SEAG000006	SEAG000007	SEAG000008	SEAG000009	SEAG000010
	NE 4	NE (TE	NE	TE
	SEAG000011	SEAG000012	SEAG000013	SEAG000014	SEAG000015
	Output: C:/Users/jackson.dalby/	Desktop/TrueViewData	/TV540/132SN023		Copy
		100% Match proj	ect data finished.		Сору



Type AATO	SYSTEM 469	.47GB is available LIDAF	469.47GB is availabl	e CAMERA 472.100	BB is available C Rei
N 124180200002				Stored: 476 can store: 4	(1) For
Carrier UAV_M350 -					🗒 us
ject	Camera Scanner	POS			
Select All					
p@2024-06-26-1 <mark>51</mark> 840	Contraction of the second seco				Carl Barner
ഉ@2024-06-19-171009	and the second second		a and		
0@2024-06-19-131942	SEAG000339	SEAG000340	SEAG000341	SEAG000342	SEAG000343
	SEAG000344	SEAG000345	SEAG000346	SEAG000347	SEAG000348
	SEAG000349	SEAG000350	SEAG000351	SEAG000352	SEAG000353
	Output: Q:/				Concel
		24.85% Projects are	copying.Do not unplug the disl	(!	Cancer

Data Copy						_ ×
Type And	SYSTEM	469.47GB is available LIDAR	469.47GB is available	CAMERA 472.100	B is available	C Reload
SN 124180200002				Stored: 476 can store: 4	0252	🔁 Format
Carrier UAV_M350 💌				Stored, 470,0811 Store, 4		🗒 USB Exit
Project	C 🗐 Info					
Select All						
@@2024-06-26-151840				-	Carl Contraction	^
@@2024-06-19-171009				Prod.		
@@2024-06-19-131942	(?	Data copying finished. Do you want to exit the	Card?	0342	SEAG000343	
					Ens	
			ОК	Cancel	1 500 5	
	SEAG00034	4 <u>SEAGUUU345</u>	SEA0000340	SEA0000347	SEAG000348	
	SEAG00034	9 SEAG000350	SEAG000351	SEAG000352	SEAG000353	~
	Output: Q:/					
		100% Data	copying finished.		Cop	у

Picture number: 148 Collect time(min): 10.9 Missing picture number: 0 Missing POS number: 0

7.2.1 Disk Format (Clearing Storage Space)

If the disk storage space is insufficient, user can click "Format" icon on the upper right corner to format the disk. This format will only delete project data, but not delete default parameter folder.



Format	×
SYSTEM ALPHA_SYS(E:/)	469.47GB is available
LIDAR	
ALPHA_SYS(E:/)	469.47GB is available
CAMERA	
ALPHA_CAM(D:/)	472.10GB is available
Please select disk to format	Format

- Note: If either of the disks' memory is less than 10% or cannot meet storage requirements, the user will need to clear disk memory in advance.
- **Note**: User can only format disk via data copy tool, otherwise, the default folders inside disk will be deleted, which will cause error.



7.3 USB Exit

After data copy finished, click "USB Exit" to eject disks first, then disconnect type-C cable between TV540 and PC.



Picture number: 148 Collect time(min): 10.9 Missing picture number: 0 Missing POS number: 0

7.4 Data structure

The Data copy tool will create a project folder with defined structure automatically after data copy. Details can be seen in the figure below:



The data project folder will be named based on capture date & GPS time by default, for example "@@2021-07-30-030325". There are four folders: GPS, IMG, SCAN and TRACE.

3/7/2022 4:00 PM	File folder
3/7/2022 4:00 PM	File folder
3/7/2022 4:01 PM	File folder
1/28/2022 12:09 AM	File folder
	3/7/2022 4:00 PM 3/7/2022 4:00 PM 3/7/2022 4:01 PM 1/28/2022 12:09 AM

7.4.1 GPS

The GPS folder stores GNSS, IMU and processed POS data. It contains six sub-folders:

🚬 Base	2023/6/12 13:39
Ctrl	2023/5/9 8:48
📁 Post	2023/8/15 15:35
Nover 1	2023/6/1 17:37
📁 Rtk	2023/5/9 8:48
Sync 🔁	2023/5/9 8:48

• The base folder stores static data from the base station. It is empty by default.

• Ctrl folder stores GCP files. It is empty by default. User can choose to save GCP files here for data management purposes.

• Post folder stores trajectory file (.PosT format). It is empty by default.

• Rover folder stores LiDAR GNSS & IMU data. Those files will be stored automatically after the data copy is finished.

RTK & Sync are reserved folders. They are empty by default.

7.4.2 IMG

IMG folder stores captured picture data with .CP calibration file under "Camera1" folder. The raw pictures are not geo-tagged. After picture processing is finished in LP360 software, it will store renamed geo-tagged images.

7.4.3 SCAN

SCAN folder stores captured laser raw data files with .EP calibration file under the "Scanner1" folder. The raw laser data is .ltp format.

7.4.4 TRACE

TRACE folder is a reserved folder. It is empty by default.



8 TV540 Authorization Guide

If the device license is about to expire, please contact the GeoCue Support team for registration extension or a permanent license. The support team will provide a "lic_code.bin" file. The user will need save it under ALPHA_SYS disk, then power on TV540 and it will finish registration automatically.

ALPHA_SYS (G:) >			
ı́m ↑↓ Sort ~			
Name	Date modified	Туре	Size
code_124180200002.bin	8/21/2024 6:08 PM	BIN File	1 KB
devinfo_124180200002.lic	8/21/2024 6:10 PM	LIC File	1 KB

User can open the "lice_info" file to check the updated expired time.

ALPHA_S	YS (G:) →			
) ¢	🔟 🛝 Sort - 📰 View -			
*	Name	Date modified	Туре	Size
*	20240619	6/19/2024 5:17 PM	File folder	
*	20240626	6/26/2024 3:18 PM	File folder	
	🔁 СРХ	5/12/2024 10:47 PM	File folder	
	EPX	5/12/2024 10:47 PM	File folder	
	📒 lic_backup	6/19/2024 1:18 PM	File folder	
	NewPARAM	6/19/2024 12:23 PM	File folder	
	detect.bin	8/21/2024 6:10 PM	BIN File	1 KB
	lice_info	8/21/2024 6:10 PM	File	1 KB
	G:\lice_info - Notepad++	guage Settings Tools Macro	Run Plugins Wir	ndow ?
			8 68 🎝 1 運 (z 🔊 🖷 🖉 🖿 🤇
	🔚 lice_info 🗵			
	1 2054-05-09	,W3878,S518	418.	
	2			

Users can also check the authorization status through the webpage.

=	TRUEVIEW 540			🛪 🗘
¢	Settings	Device Info		
Ħ	Status	SN	PN	
()	About	124110200004	S20410076624204001	
	CLOSE PROJECT	Firmware Version 1.0.24	Authorization Expired Date 2037-11-27 AUTH	
	START COLLECT	Based on open source software © 2024 GeoCue		



9 Additional Information

9.1 Important Notes

The LiDAR measurement system is complex and precise survey equipment. In daily carrying, using, and storing, please operate equipment correctly and maintain properly. There are some important notes listed below:

 Do not disassemble equipment. If equipment has an issue, please contact the GEOCUE support team.

 Please use the provided default accessories. The use of non-original accessories is not eligible for a warranty.

Avoid any strong impact or vibration.

If it is needed to continue using the instrument for a long period of time or under special conditions, such as high humidity environment, please consult with the GEOCUE support team in advance. Generally, the damage that occurred under inclement environmental conditions is not covered by the product warranty.

9.2 Product Transportation

 Please use the GEOCUE TV540 product equipped special container for transport. During transportation, make sure the container is fixed in a stable location.

 During transportation, please notify shipping personnel that this is precise system container and it needs to be handled gently. Also, attach fragile labels on the container.

If the equipment is sent by express service, the container needs an outer box with foam inside also for safety.

 When transporting or moving batteries, take proper measures to prevent materials from falling or damaging.

9.3 Usage Tips

The equipment should be handled gently during use to avoid soiling and scratching its surface. Please do not sit on the container.

After the external test or operation, the surface of equipment should be cleaned regularly by using the provided cleaning equipment (at least every 3-5 days), check whether the structural screws and plugs are loose, and whether the peripheral cables are loose.

If the unit is in long term storage, it needs to be taken out regularly (once a month) for power-on test to check whether the function is normal.

- The limitation of the environment temperature is between -20 °C to +50 °C.
- If the equipment is disassembled or loosened, it should be re-calibrated.

When it is difficult to rotate any of the rotating parts of the equipment, please do not forcibly rotate.



• After the equipment is damaged, please do not continue using. Do not disassemble equipment in the field.

• If faced with rain or snow in the field, please move the equipment into the container quickly.

9.4 Storage Tips

- The room where the equipment is stored should be clean, dry, and well a ventilated area.
- It should be placed flat or upright. It should not be stored in a "leaned" position.



10 Frequently Asked Questions

Equipment cannot power on or power off normally: Check whether the drone platform power supply and connection port are normal. If the unit still cannot power on or off, please contact the GEOCUE Support team for repair.

• Unit is unable to get a GNSS fix or takes a long time to get a fix: Check whether the GPS cable connection is stable.

• When connecting to the device using a mobile device's Wi-Fi function: If the user cannot access the webpage, user may need to disable mobile data on device to connect properly.

If the images appear dark, check the camera's shutter settings to ensure they are appropriate.

11 Appendix

11.1 Replace DJI M300/M350 Shock Absorbing dampeners

Pictures	Name	Pcs
	Shock-absorbing dampener module	6
	M4 allen wrench	1

Note: Since the maximum load weight of the original shock-absorbing dampener of the DJI M300/M350 is less than 1Kg, it is necessary to replace the original shock-absorbing dampener.



> Take out the shock-absorbing dampeners from the transport container (slot 4).

As shown in the following figure, remove the 4 original shock-absorbing dampeners from M300/M350 using the provided M4 allen wrench (it is recommended to replace all the original shock-absorbing dampeners one by one). Push the shock-absorbing dampeners from the groove edge towards the center. Repeat this process a few times until it comes off. Avoid pulling or yanking with force, as it may cause damage to the dampener.





When removing the shock-absorbing dampener, use the round end "1" to remove it. Do not use the right-angle end "2" to remove it, as it may damage the shock-absorbing dampener.



Replace all the original shock-absorbing dampeners one by one. When installing the new shock-absorbing dampener, insert the bottom rubber ring down first, then insert the top rubber column from the top bracket and pull the rubber column up.



1- Top rubber column; 2- Bottom rubber ring



It is recommended to install a new shock-absorbing dampener every time the user removes an original dampener to prevent the load plate from falling off or becoming misaligned.

11.2 DJI M300/M350 Installation Steps

Push the "Alphaport" slider of scanner into the quick-release clamp of the bottom of the airborne mounting platform in the direction of the arrow until a "click" sound is heard.



1- quick-release clamp; 2- Alphaport

Tighten the side screw bolt to make it stable to finish the installation.





Align the white dot on the device Skyport interface with the red dot on the M300 interface and insert it in the installation location. Rotate the device SkyPort interface to the locked position (red dots align red dots) to be fixed.



Insert the rod antenna into the antenna mount and tighten it.





11.3 Installing TV540 On Other Platforms

If install TV540 on a third-party aircraft, it is necessary to measure the Lever Arm Offset value from Sensor Measurement Origin to Antenna Phase Center.

11.3.1 How to measure Lever Arm Offset

Measure the Lever Arm Offset value from Sensor Measurement Origin to Antenna Phase Center. The Sensor Measurement Origin is where the measurement should originate. Please refer to the actual antenna phase center as well:

- "M" is Sensor Measurement Origin on TV540 (LED indicator light).
- X is right, Y is forward, Z is up direction. If the direction is opposite, then value is negative.

For example: If using the default antenna (AV14), then TX = -0.08811m, TY = -0.15469m, TZ = 0.29336m.



11.3.2 How to generate a new TV540 profile in LP360

Click"Tools->Data Copy"

Project	Sensor Map Control Points	Point Tasks QA/Q	C Classification Feature	Edit Cloud Support		^	(LP360) [12,265.
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Select User Defined when copying data:

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Set parameters as shown below.

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postive, upward is negative)	0.0000
For details please refer to the	hardware device manual	

- Carrier Type: Select the original payload.
- Carrier Name: Rename the new payload type.
- Lever Arm Offset (Sensor Measurement Origin to Antenna Phase Center; Unit: meter): Enter the values from original point M to antenna phase center.



 Installation Direction (Unit: degree): Flight direction to A-port direction (Same/Opposite): If the flight direction is the same direction as the Y-axis, select same.



• A-port to the horizontal direction rotation (Down is positive, up is negative). If the device has no angle, value is 0, as follows:





• A-port to the horizontal direction rotation (Down is positive, up is negative). If the device has angle, as follows, value is -8:





Support

Our searchable support knowledge base contains information on workflows, tips, hints, and probable resolutions to error messages or commonly encountered situations.

https://support.geocue.com/

Normal support business hours are Monday - Friday, 8 AM — 5 PM USA Central Time.

Our GEOCUE Support website contains general workflow information, in addition to specific issue and error messages that you may encounter. Click on the link and search for information contained in the knowledge base.

If a support request is sent during business hours a representative will typically get back to you within 4 hours. If received after hours, a response will be sent the following day. To speed response time please include the following information in your request:

- Contact information please include e-mail address and phone number
- Company name
- Product name and version number
- True View Model and Serial Number

If your request includes problems pertaining to a specific error message, please include a screenshot of the error message.

For hardware and software support contact: support@geocue.com