

Eagle 120

60 Lines **Solid-State Flash** Lidar

Product Manual

2024-11



About the manual

■ Using tips

- Please be sure to read the manual carefully before use the product, and operate the product following the instruction to avoid product damage, damage to other property, personal injury or violation of warranty terms
- This manual does not contain the product authentication information, please check the authentication information at the bottom of the product brand, and query the corresponding certification reminder.
- If this laser lidar products is used as part of your product, please provide this manual to your product expectation users, or provide the acquiring method of the manual.

■ Technical support

If the manual can't solve the problems, please contact us through the following way:
info@lidarengineering.com

■ Legend

- Warning: be sure to follow the safety instructions or the correct operation method.
- Attention: supplementary information, for better usage of the product

Safety warning

■ Laser safety

	Laser Safety
	This product will emit invisible laser during operation, please avoid eye damage during operation. This product pass the Class 1 safety level and will obtain the human eye safety CB certification, according to the EN60825 requirement, it will not damage the human eye and body during normal operation. Please use the product correctly!(Avoid direct view to the Lidar)

Attention: This product hasn't obtain the human eye safety CB certification, please pay attention to the laser impact to the human eye safety; For another product series XT-S240 Pro already obtained the human eye safety CB certification

Human eye safety

This is the laser product, in order to protect the user, it's strongly recommended that avoiding the direct view to the laser through the magnifying equipment (like microscope and any kind of magnifying lens) during product operation.

This product have no power switch, it will operate once the power is connected;

During the product operation, the whole light cover can be treated like the laser emit area, direct look to the light cover could be treated like the direct view to the laser during operation.

■ High temperature

Avoid direct contact with the products shell during the product operation or right after the product operation.



Please check the working temperature within the chapter "technical parameter" of the user manual, avoid the working environment which exceed the working temperature.

Operating in the environment like high/low temperature, strong vibrations, heavy fog etc. might reduce the Eagle 120 performance.

In addition, long working time in the high temperature environment might impact the product performance or even damage the product.

It's strongly recommended that user add radiating precaution to make sure the shell temperature won't exceed 60 degree.

If the product temperature is too high, it will trigger the high temperature self-protection mechanism, Eagle 120 will send out the high temperature warning, if the temperature is too high, Eagle 120 will stop the operation, and restart only after the temperature reach the normal level.

Recommend storage environment:

Dry and ventilated environment, temperature $23\pm5^{\circ}\text{C}$, humidity 30%~70%.

■ Abnormal stop

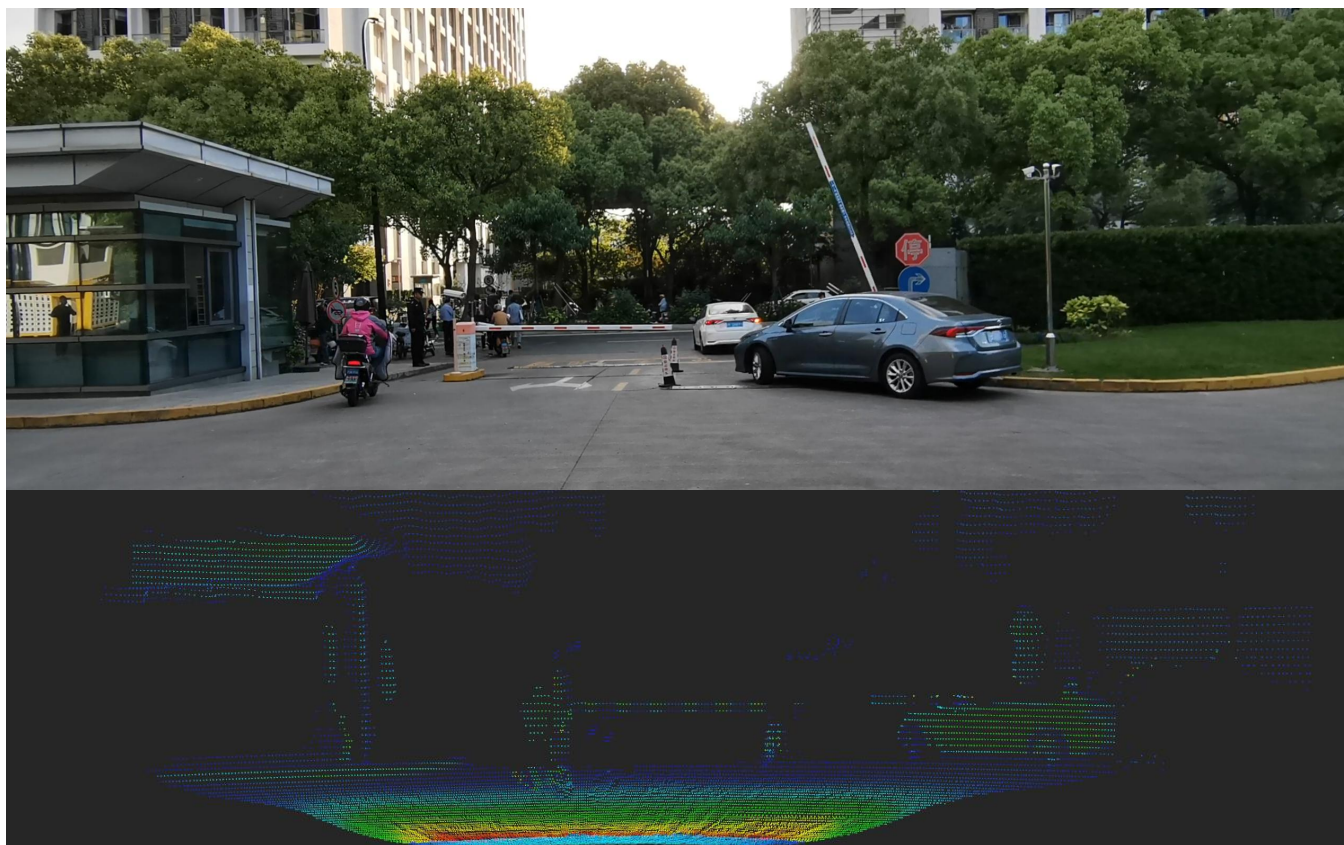
If occur the following circumstances, please immediately stop using the product.

- Suspect product failure or damage, for example, the product have obvious noise, smell or smoke
- User or people around feel any discomfort of themselves
- Abnormal running equipment in the surrounding environment

■ Disassembly prohibited

Without the written consent of Toffutre, disassembly is explicitly prohibited of this product.

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Product introduction

The Eagle 120 is a cost-effective, safe and reliable **pure solid state flash** blind detection lidar. It can be widely used in industry of engineering machinery, unmanned aerial vehicle, intelligent traffic areas, such as AGV, UAV, intelligent security robot, vehicle blind detect and corner lidar etc.

Product highlights

Solid State :	No mechanical parts, reliable
The ultra small size :	65 mm * 38 mm * 45 mm
120 Line :	The equivalent of 60 lines, 9600 pixels/frame Angular
Angular Resolution:	0.75 ° * 0.75 °
Anti-blooming:	In the 100Klux sunlight environment can work properly and provide stable point cloud
Multiple images:	3D point cloud, depth, the infrared gray, incredible figure, etc
Multiple inter faces:	Waterproof interface
Waterproof dustproof :	IP67
Automotive Grade:	Mature silicon semiconductor technology, reliability, consistency, stability, security, high integration, simple structure, low fault rate and meet the mass demand of clients

1、The product features

1.1 Working principle

The distance measurement principle is the Flight Time measurement (Time of Flight).

- 1) Emit ultrashort laser pulses.
- 2) Laser reach the object and reflection, photosensitive receiver receives the reflected light.
- 3) By measuring the flight time of the laser in the air, we can accurately calculate the distance between target object and the sensors.

ToF is the abbreviation of Time - of - Flight, the Flight Time of light, essentially it is one kind of depth range camera to provided the high quality depth image, ToF, the structure light and the eyes constitute three mainstream of 3D visual technology.

iToF is the abbreviation of indirect Time - of - Flight, dToF is the abbreviation of direct Time - of - Flight.

For iToF, it has high resolution, high accuracy performance. On the other side, for dToF, it has high sensitivity and long detection range. For differnet application, different technical approach could be taken.

$$d = c * t / 2$$

d: Distance
c: Speed of Light
t: Fly time of the laser pulse

Figure1.1 ToF distance calculation formula

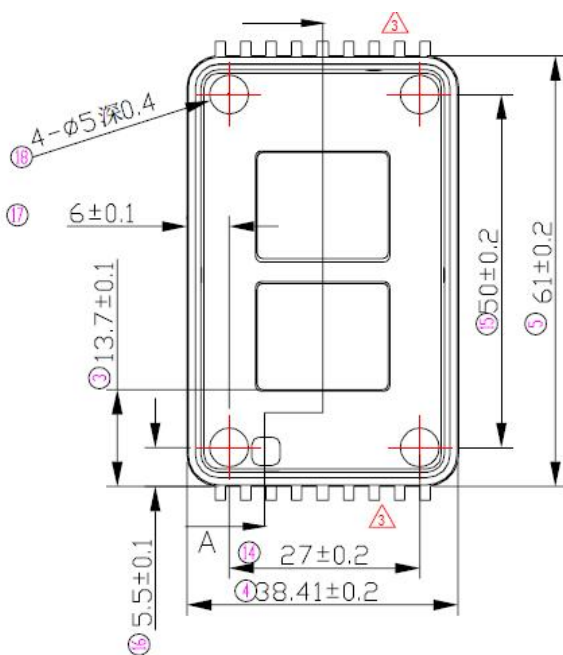
1.2 Technical parameters

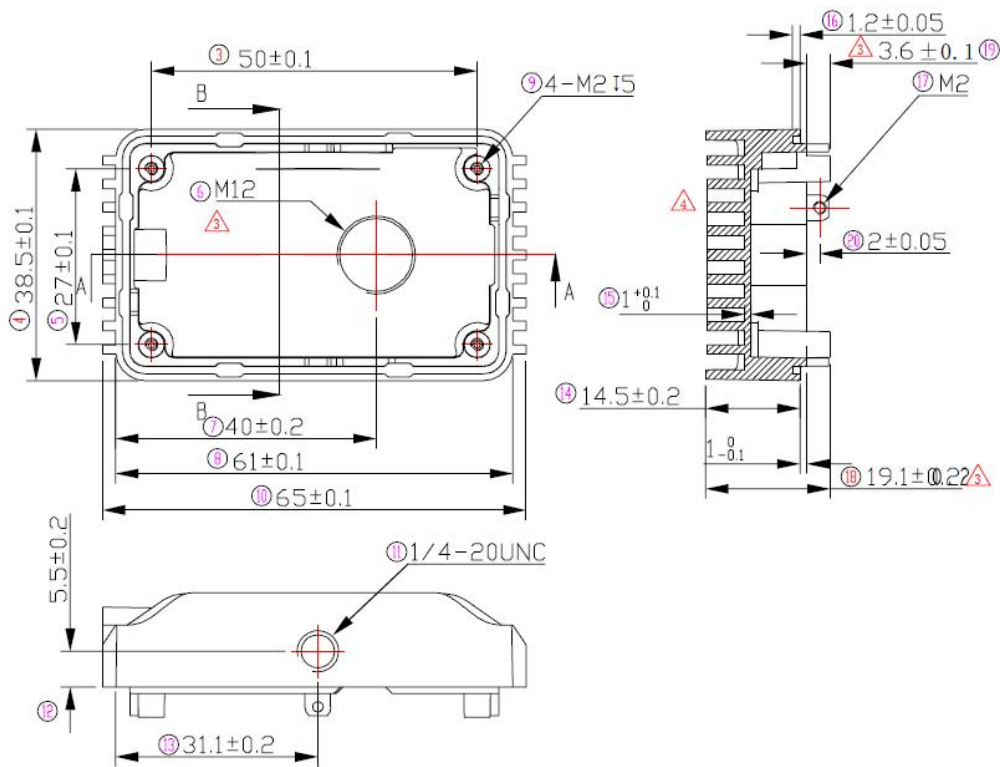
Product series	Scene	Product Name	Viewing Angle Fov1	Viewing Angle Fov 2	Frame Rate	Optical Wavelength	Average Power	SDK	Output Data	Angular Resolution	Measuring Distance	Dustproof Waterproof	Volume mm	Weight	Power Supply	Operation Temperature
M series (medium to long distance)	Medium And High Speed	M60	120x45°	130°x52°	1-30 Frame	940nm	6w	C++ /Linux /Ros1&2	Infrared image Depth image, 3D Point cloud	0.75°H x0.75°V (160x60)	15m@50% 7m@10% Outdoor (0.3~20m Indoor)	IP67	65x35x45	123g	12-24V@3A Aviation Interface	-40°to85°
Customized Products	Low Middle High	M Series	106°x30° 60°x45° 32°x24°	110°x30° 58°x49° 40°x30°	1-40 Frame		6-12w			60-240 Line	30\50\100m	Customized	TBD	TBD	TBD	TBD

Special Reminder:

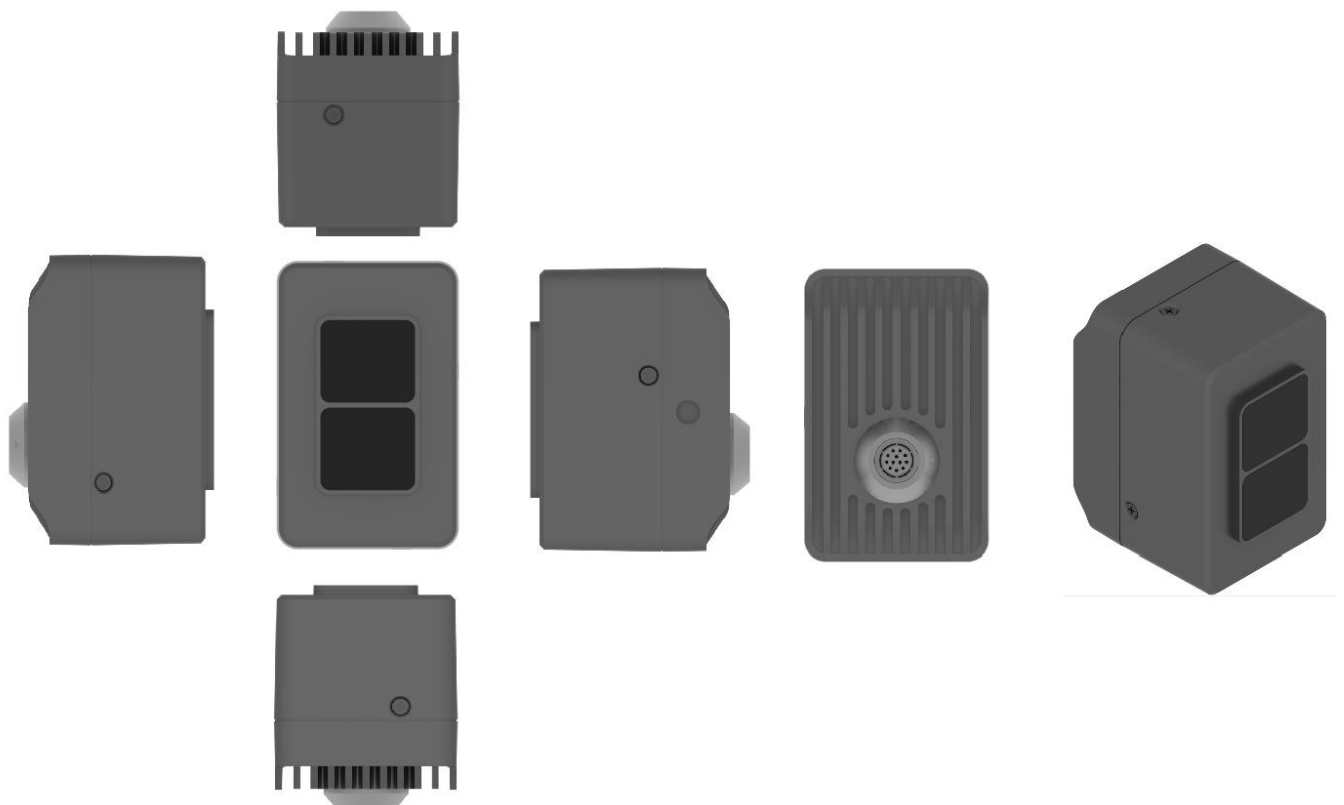
1. FOV1, represent the field of view of the image receiver side, which is the angle of the output image and 3D point cloud. Using FOV1 as the parameter for image, software, algorithm, point cloud related applications.
2. FOV2 represent the field of view of the laser emitter, due to light interference and multi-path interference, FOV2 must be larger than FOV1. Using FOV2 as the parameter for the photology, structure, machinery and installation related applications.
3. Marked on the 3D models, application and question related to mould making and precise mechanical structure, please contact the technical support for confirmation to avoid unnecessary lost. Thank you!

2、Products mechanical structure





3、Product six views



Product shell

- The products are mainly made of metal, glass and copper clad, internal contain sensitive electronic components, must avoid dropping, burning and other improper operation. Once the product experience falling or burning, please stop using immediately, and contact Lidar Engineering for technical support.
- Avoid extrusion or puncture of the product. If the shell is damaged, please stop using immediately.
- Before active the product, please ensure that the product has been firmly fixed, and avoid the external force (such as the impact, wind, flying rock, etc.) which might move the product from a fixed position.

Light mask of the shell

- Do not touch the mask, lest the mask with fingerprints or dirt. If the mask is not clean already, please follow the decirbed methed in the section “instrument maintenance” of instructions to clean.
- Please avoid contact with hard or sharp object for scratches in the mask. Please stop using the product with serious scratches since it may affect the product performance.

High temperature

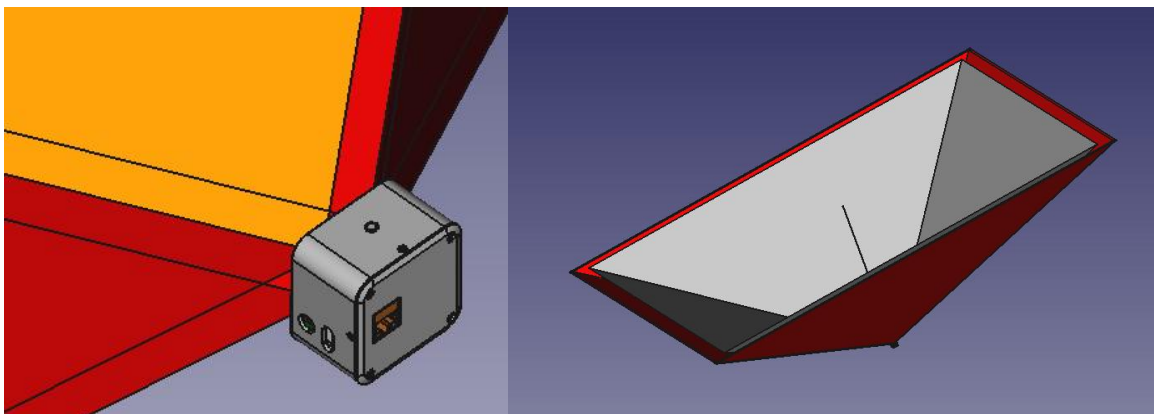
During the products operation or a certain period of time after the product operation, the product shell may be in high temperature condition, please note that:

- Avoid direct skin contact with the product shell, which might casuing the skin burned.
- Avoid direct contact with product shell using combustibile materials , which might cause a fire.

4、 Installation Angle

4.1 Effective field of view (FOV) Angle range

XT - M60 Pro FOV is $120^{\circ} \times 45^{\circ}$, pay attention to the FOV range, avoid blocking and interference. Contact the agent or info@lidarengineering.com for the FOV 3D model of the mechanical installation.



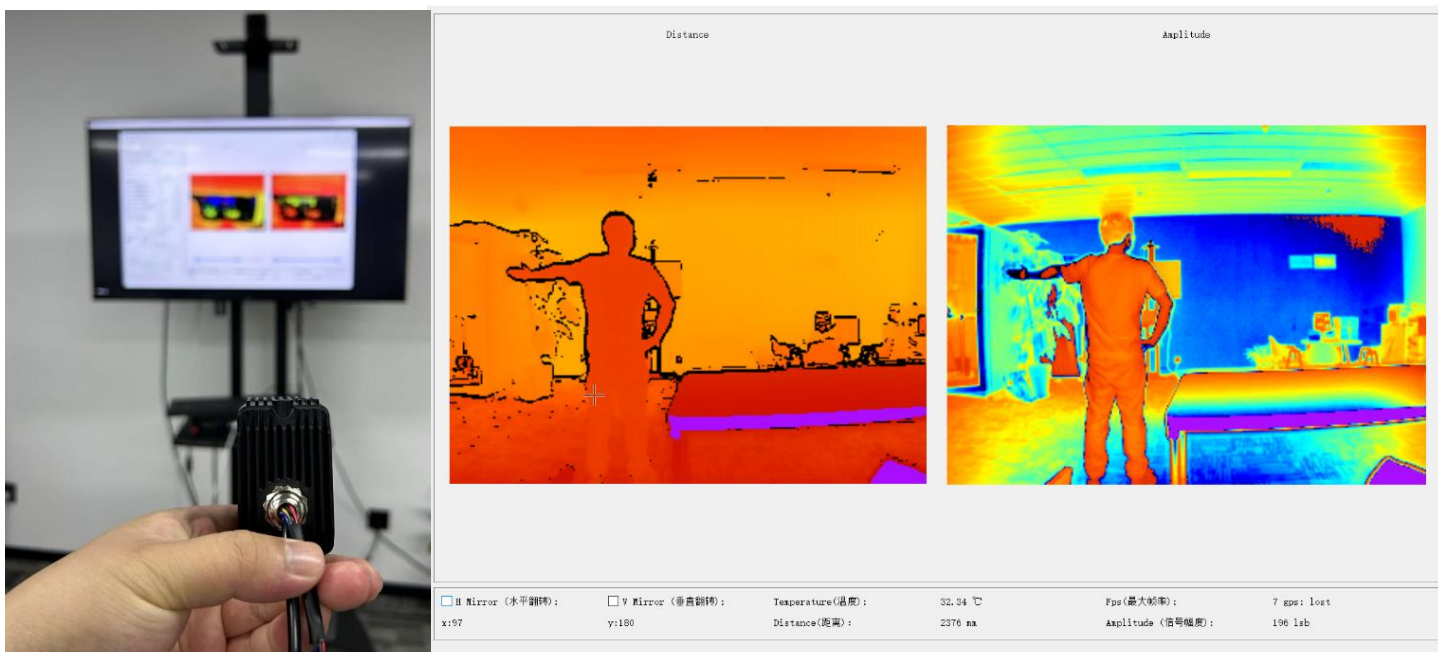
4.2 Field of view(FOV) detection range

The following model server the purpose to convenient customers to intuitive understand the detection range covering by the product (spherical coordinates) under different FOV and distance measuring range,in order to select a better corresponding FOV of products for different applications.

FOV	106 ° * 80 °	72 ° * 58 °	106 ° * 30 °	60 ° * 45 °	32 ° * 24 °
Measurement Range (@5m)	13.3m * 8.4m	7.3m * 5.5m	13.3m * 2.7m	5.8m * 4.1m	2.9m * 2.1m
Measurement Covered Area	111.4 m ²	40.3 m ²	35.6 m ²	23.9 m ²	6.1 m ²
Measurement Range (@10m)	26.5m * 16.8m	14.5m * 11.1m	26.5m * 5.3m	11.5m * 8.3m	5.7m * 4.3m
Measurement Covered Area	445.4 m ²	161.1 m ²	142.2 m ²	95.7 m ²	24.4 m ²
Measurement Range (@20m)	53.1m * 33.6m	29.1m * 22.2m	53.1m * 10.7m	23.1m * 16.6m	11.5m * 8.5m
Measurement Covered Area	1781.6 m ²	644.4 m ²	568.9 m ²	382.6 m ²	97.5 m ²

4.3 Module installation angle

Look forward from the back side of the module, install the module on the tripod, aviation plug on the right side(red circle)



4.4 Coordinate

4.4.1 Camera mode(default):

Camera defined that the oppsite side of the lidar data cable(avaition plug) is the front side. “Z” point to the front side of the lidar, “X” point to the left side of the lidar, “Y” point to the sky.



4.4.2 Lidar mode(Car):

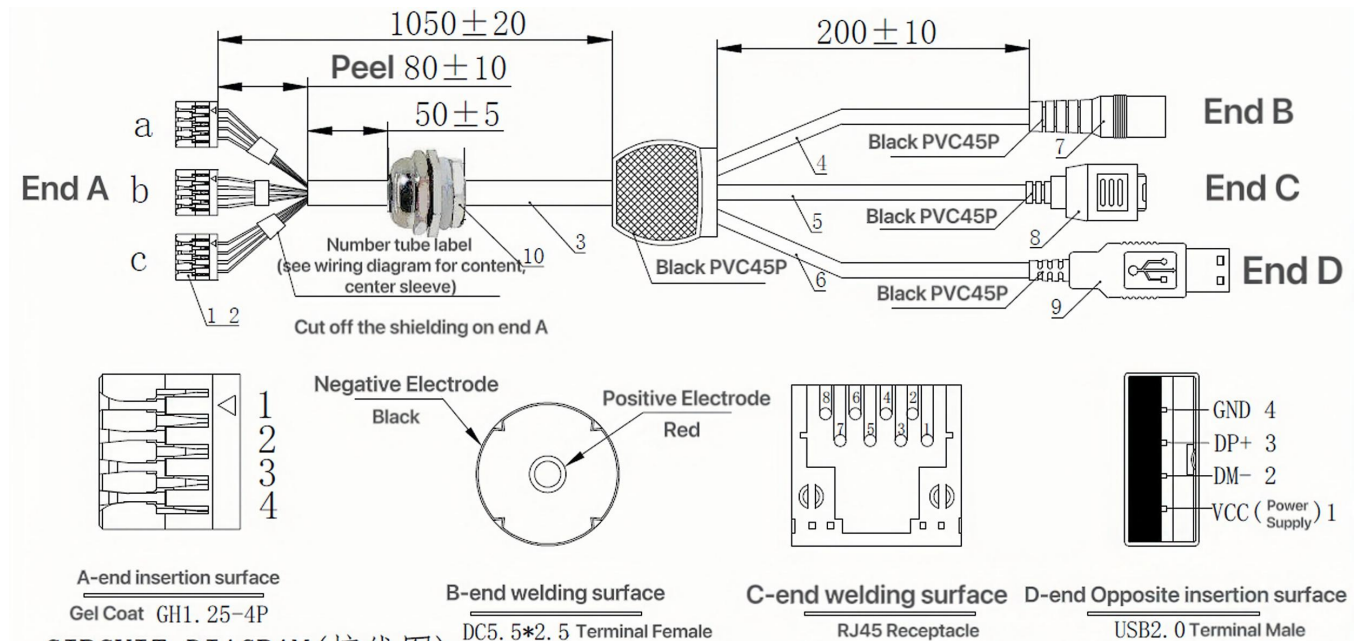
Car defined that the oppsite side of the lidar data cable(avaition plug) is the front side. “X” point to the front side of the lidar, “Y” point to the left side of the lidar, “Z” point to the sky.



5、 Installation and operation

The power supply

·Recommend to use power supply cable and power adapter offered by Tofftute.



• For the customer design, configuration or selected power supply system (including cables) by themselves, please follow the relevant electrical parameters in the instructions, or contact the Tofftute for technical support. Using damaged cable, adapter or the power supply which dose not meet the requirement is forbidden.

·It's recommend to use the cable and power adaptor provided by Lidar Engineering

Power Supply: Delippo	Website	
19V 3.42A stable version	https://item.jd.com/100049765921.html https://m.tb.cn/h.gN2RnKYC1UDVUDv?tk=39VP34LBdYc	

12V 3A low voltage supply and small version	https://item.jd.com/100047619867.html	
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Waterproof plug

- M12 plug line sequence and pin definition as below:

2. CIRCUIT DIAGRAM (Wiring Diagram)

	End A			Number Management Content	Definition
Twisted Pair	a-1 white	1 orange	End C	Network Interface	TD_P
	a-2 black	2 orange white			TD_N
Twisted Pair	a-3 white	6 blue			RD_P
	a-4 grey	7 blue white			RD_N
Twisted Pair	b-1 white	2 white	End D	USB	DM
	b-2 purple	3 green			DP
Twisted Pair	b-3 white	4 black			GND
Twisted Pair	c-1 white	red / rush pith	End B	DC Power Supply	GND
	c-2 green				GND
Twisted Pair	c-3 white	black / rush pith			V+
	c-4 yellow				V+
		shell / shield			

Electrical interface

- Before power on, please make sure that the electrical outlet is dry and has no dirt. Please do not power on the product in the humid environment
- Please strictly follow the connector plug operation instructions. If you have already found abnormal interface (such as pin skewed, cable breakage and screw loosening, etc.), please stop using the product and contact Toffuture for technical support.
- Before you plug connector, please disconnect the power supply. Hot plug can lead to damage.

6、Component description



1. Lower baffle Vcsel launch window, light through the window for launch, detect the objects within FOV range.
2. Upper baffle is sensor receiving window, receiving the reflected light reflected from the object.
3. Waterproof Interface, which has:
 - a. 100 BasT card, provide laser lidar data output
 - b. DC interface, power 12V - 25V (current above 5A)
 - c. USB interface, USB with laser lidar data output
4. M2 screws, outside the module using this Type of screw
5. Universal 1/4 threaded hole

7、Data output

This protocol is based on TCP/UDP

default lidar TCP port: 7787

default UDP port: 7687

7.1 Three different types of communication data:

- Video data with large data flow,

Due to the consideration of the real time requirement, UDP protocol has been chosen. UDP data is transmitted by the lidar and accepted by the upper computer.

- lidar command interaction,

Due to the requirement of the clear result of the execution interaction and the small amount of the data, TCP protocol has been chosen to secure the interaction integrity.

- Debug log information reported by lidar,

In order to make sure the upper computer received the debug log data, and with the small amount of the data flow, TCP protocol has been chosen.

Checking the connection between the lidar and upper computer:

Option 1: Checking the heartbeat by checking the TCP connection

Option 2: Upper computer sends the command in a certain period, checks the time of the last received command by the lidar

7.2 Communication packet format(based on TCP/UDP/USB) packet format definition

Start	data packet size	data	End
4Bytes(0x7EFAA55)	4Bytes	0-30720	4Bytes(0xFF7E55AA)

Start	data packet size	ID	Command data	State code	Protocol version number	End
4Bytes(0x7EFAA55)	4Bytes	1Byte	0-307200	1 Byte(b4-b7: state code b0-b3: command return code)	1 Byte	4Bytes(0xFF7E55AA)

Using the network order(big endian as the byte order of the data).

Using the little endian for the storage in lidar and upper computer

TCP/UDP level has the checksum for the network data, as the result the XT packet doesn't contain the checksum

Dividing one frame data into multiple UDP packets to transfer (20 bytes packet header + 1400 bytes data), Because each network packet size is smaller than MTU

7.3 Data flow

Data include: depth, amplitude, grayscale, temperature, time

Output type:

1. depth + temperature + time
2. depth + amplitude + temperature + time
3. grayscale + temperature + time

Since one frame data is divided into multiple data packets, after receiving the data packets, it must be reformed into one complete frame to be used. Upper computer SDK convert the distance data coordinate into point cloud data.

Data format of one frame:

cmdid	output type	frame number	resolution	data	temperature	time mark	integration time	reserve	state code	version
1 Bytes 251	1 Byte	2 Bytes	4 Bytes	0-307200 Bytes pixel data	2 Bytes	8 Bytes Unit:us	8 Bytes	32 Bytes Device state info	1 Byte	1 Byte
Position: 8+0	8+1	8+2	8+4	8+8	8+8+Dsize	8+8+Dsize+2	8+8+Dsize+10	8+8+Dsize+18	8+8+Dsize+51	8+8+Dsize+52

Pixel format:

Output type	Description	Byte size
1	Depth	2 Bytes
2	Depth + Amplitude	2Bytes + 2Bytes
3	Grayscale	2Bytes

UDP packet division

One complete frame data will be divided into multiple UDP packets before transmission, receiver will reform the UDP packets to the complete frame data

UDP packet structure

Packet Head	Data
20 Bytes	Max 1400 Bytes

UDP packet header structure

Frame number	Frame size	Packet data size	transmitted size	Packet number in total	Packet number
2 Bytes	4 Bytes	2 Bytes	4 Bytes	4 Bytes	4 Bytes

Attention: the data flow contain PTP synchronization time information

Command Response State Code

Device state code: **DevStateCode**

id	Description
0	Unconnected
1	Device Initialization
2	Device Idle
3	Device Busy
4	Error: CSI interface
5	Error: I2C interface
6	Error: temperature too high
7	Error: temperature too low

8	Error: unknow
9-15	reserve

command response code: **CmdRespCode**

id	Description
0	Command excecute OK
1	Command unsupport
2	Device busy
3	reserve
4	reserve
5	reserve
6	reserve
7	Report message
8	Error: Command format/size/value
9	Error: Command data
10	Error: CSI interface
11	Error: I2C interface
12	Error: temperature too high
13	Error: temperature too low
14	Error: unknow

7.4 Command data

Command/Response/active report and same format

Blue fint showing the data size of current command, which will not be trasmitted, the packet size will contain the data size information

Command ID	data	datasize
1 Byte	..	0 Byte

7.5 Command list:

Command	ID	Parameter	Description
Image	251		Send out one frame of the image data
Start	1	Type	Start measurment
Stop	2	-	Stop flow
Set IP address	3	IP address, subnet mask, network management IP	Set the internet address
Request device infomration	4	-	Internet infomration, device version, product serial number, chipid, calibration status
Request configuration information	5	-	Output image type, frequency, HDR, integration time, min amplitude, filter status
Set filter	6	Edge, Temporal	Set the filter function which to be open and the filter parameter
Set integration time	8	4 group integration time parameter, grayscale integration time	HDR compatible
Set min signal amplitude	9		Discard the signal with too low amplitude
Set HDR	10	Type	
Reset	13	Fixed string "XINTAN"	Reset the lidar
Set modulation frequency	52	Frequency number	12m, 6m
Set ROI	51	x0,y0,x1,y1	
Trace output	209	Size, string	Send out the log information

7.6 Command type:

Blue fint showing the data size of current command, which will not be trasmitted, the packet size will contain the data size information.

	Command ID	Data	Data size
Flow Data	251		0 Byte

Start	Command ID	B0	B1	Data size
Command	1	Image type 1:Depth 2:Depth+Amplitude 3: Grayscale	Once/flow 0/1	2 Bytes

	Command ID	Data size
Response	1	0 Byte

Stop	Command ID	Data	Data size
Command	2		0 Byte

	Command ID	Data size
Response	2	0 Byte

Set IP Address	Command ID	Data	Data size
Command	3	IP 4Bytes Msk: 4 Bytes Gate: 4 Bytes	12 Bytes

	Command ID	Data size
Response	3	0 Byte

Request Device info	Command ID	Data	Data size
Command	4		0 Bytes

	Command ID	Data	Data size
Response	4	IP: 12 Byte Mac Address: 6 Bytes FW Ver: 18 Bytes SN: 28 Bytes Boot Ver: 14 Bytes Status: 1 Bytes Chip ID: 4 Bytes Calibration Status: 2 Bytes Reserve: Remaining Bytes	90 Bytes

Request Configuration Info	Command ID	Data	Data size
Command	5		0 Byte

	Command ID	Data	Data size
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Response	5	Output Image Type: 1 Byte Freq: 1 Byte HDR mode : 1 Byte Integration Time : 8 Bytes Min amplitude : 2 Bytes Kalman filter factor : 2 Bytes Kalman threshold : 2 Bytes Flying-spot filter threshold : 2 Bytes Reserve: Remaining Bytes	30 Bytes
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Set Filter	Command ID	Data	Data size
Command	6	Kalman factor: 2 Bytes(0-1000), '0'means closed Kalman threshold: 2 Bytes(0-2000), '0'means closed Flying-spot threshold: 2 Bytes,'0' menas closed	5 Bytes

	Command ID	Data size
Response	6	0 Byte

Set Integration Time	Command ID	Data	Data size
Command	8	4 groups integration time, 2 bytes for each group	8 Bytes

	Command ID	Data size
Response	8	0 Byte

Set Min Amplitude	Command ID	Data	Data size
Command	9	Unit 16 value (0-2000)	2 Bytes

	Command ID	Data size
Response	9	0 Byte

Set HDR	Command ID	Data	Data size
Command	10	0: closed 1: Space HDR 2:Time HDR	1 Byte

	Command ID	Data size
Response	10	0 Byte

Reset	Command ID	Data	Data size
Command	13		0 Byte

	Command ID	Data size
Response	13	0 Byte

Set Frequency	Command ID	Data	Data size
Command	52	0: 12M 1: 6M	1 Byte

	Command ID	Data size
Response	52	0 Byte

Trace Output	Command ID	Data	Data size
Command	209		X Bytes

Version History

Version	Description	Data
V1.0	First Version	20241114