

Project report

Date: Tue Jul 20 2021 15:39:53
Build with: Z+FLaserControl 9.0.2.24038
Project: Bis. Sf.Vineri
Master scan position: 1

117 of 117 scan positions used for registration.
117 of 117 scans registered.

Quality standard deviation of the cloud to cloud registration

d:3.61 mm

Superior matrix

1.000000	0.000000	0.000000	0.0000 m
0.000000	1.000000	0.000000	0.0000 m
0.000000	0.000000	1.000000	0.0000 m
0.000000	0.000000	0.000000	1.0000

Scan position '1'

Scan position is member of group(s):

Status registration '[13h] registered, compensated'

Registration matrix:

0.900295	0.435281	-0.000338	0.0002 m
-0.435281	0.900295	-0.000211	0.0001 m
0.000213	0.000337	1.000000	0.0000 m
0.000000	0.000000	0.000000	1.0000

Scan '1'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata Value comment operator

```
Scan comment: null  
Sensor  
sensors: 3100 *barometric translation: rotation: gps  
Barometer: 0.991733 bar ~ 80.888 m  
nav translation: 0.0000 m 0.0000 m 180.7770 m accuracies: 5.1000 m 5.1000 m 0.0000 m  
nav rotation: 0.00000 0.0000 25.8032 accuracies: 0.0000 0.0000 15.0000  
upside-down: no  
GPS lat:44.943321 long:26.029163 satellites:4 height:197.5m hdop:2.2 vdcop:5.8m hacc: ~ 7.0m vacc:13.4 flags:G3 'stand alone 3D solution'  
north:4977112.543 m east:423407.803 m zone:36T  
Initial pre position: (300..toor)  
0.900 0.435 0.000 0.000  
-0.435 0.900 0.000 0.000  
0.000 0.000 1.000 0.000  
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



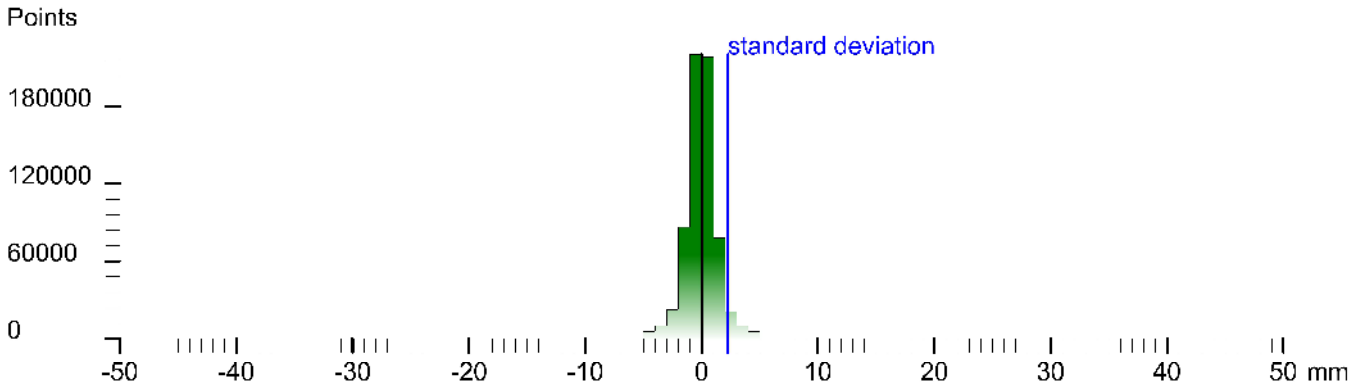
Scan position '10'

Scan position is member of group(s):
Status registration '[102h] registered with cloud to cloud'
Registration matrix:

0.881282	-0.472591	0.000060	17.5451 m
0.472591	0.881283	0.000100	6.3066 m
-0.000100	-0.000060	1.000000	0.7137 m
0.000000	0.000000	0.000000	1.0000

Result registration cloud to cloud standard deviation:2.3 mm

Deviation histogram



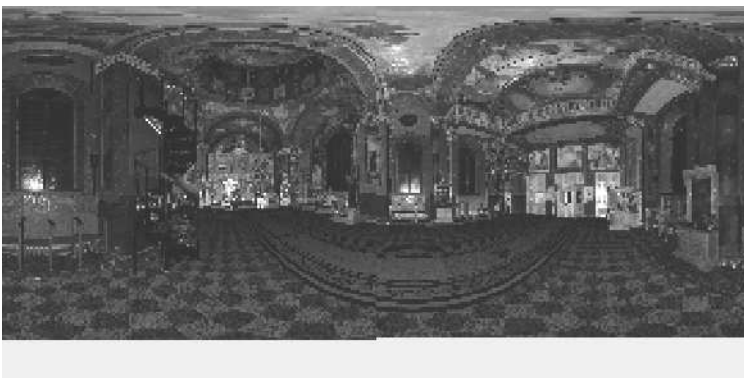
Scan '10'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Sensor: ...  
Sensors: 3096 *barometric transition rotation*  
Barometer: 0.992060 bar / 77.815 m  
nav translation: 1.7724 m -2.5906 m 177.5356 m accuracies: 0.6509 m 0.5509 m 0.0000 m  
nav rotation: 0.0000 0.0000 0.0000 0.0000 0.0000 0.0000 15.0000  
upside-down: no  
Initial position: (0/door)  
0.808 -0.418 0.000 -3.741  
0.418 0.808 0.000 -9.950  
0.000 0.000 1.000 -3.241  
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '100'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

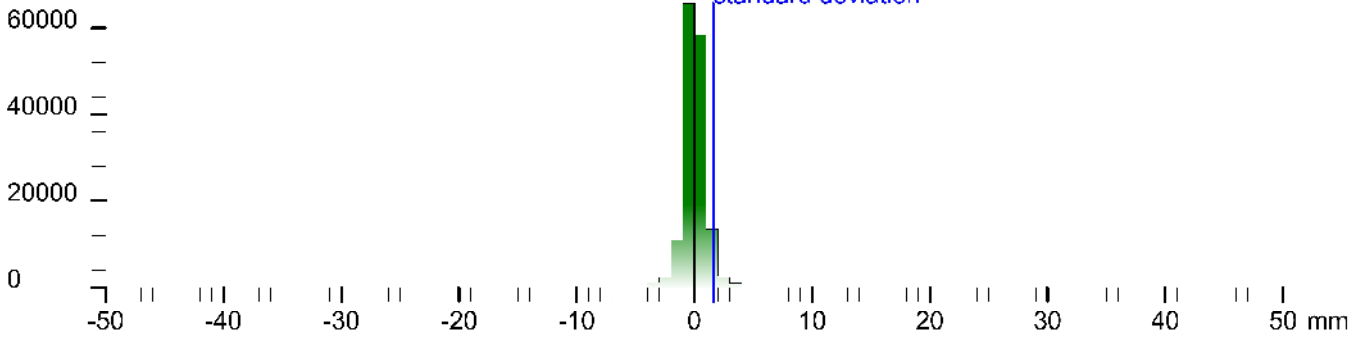
Registration matrix:

```
-0.854968 -0.518681 -0.000013 -20.0099 m
0.518681 -0.854968 -0.000582 -4.0731 m
0.000290 -0.000505 1.000000 -0.0269 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 1.6 mm

Deviation histogram

Points



Scan '100'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

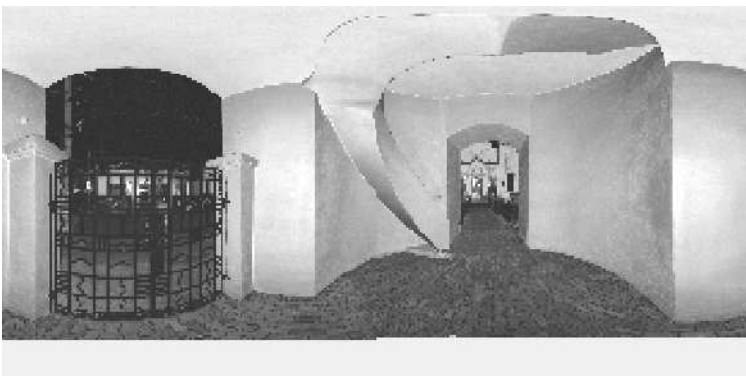
Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

Scan comment: null
Sensor

```
sensors: 3096 *barometric transition rotation*  
Barometer: 0.999644 bar ~13.89 m  
nav translation: -1.8128 m -0.3013 m 1 3.1 6/2 m accuracies: 0.0596 m 0.0596 m 0.0000 m  
nav rotation: 0.0000 0.0000 22/463s accuracies: 0.0000 0.0000 1s.0000  
upside-down: no  
Initial pre position (Girdoor)  
-3.676 -0.737 0.000 14.913  
0.737 -0.676 0.000 -8.106  
0.000 0.000 1.000 -68.548  
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '101'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

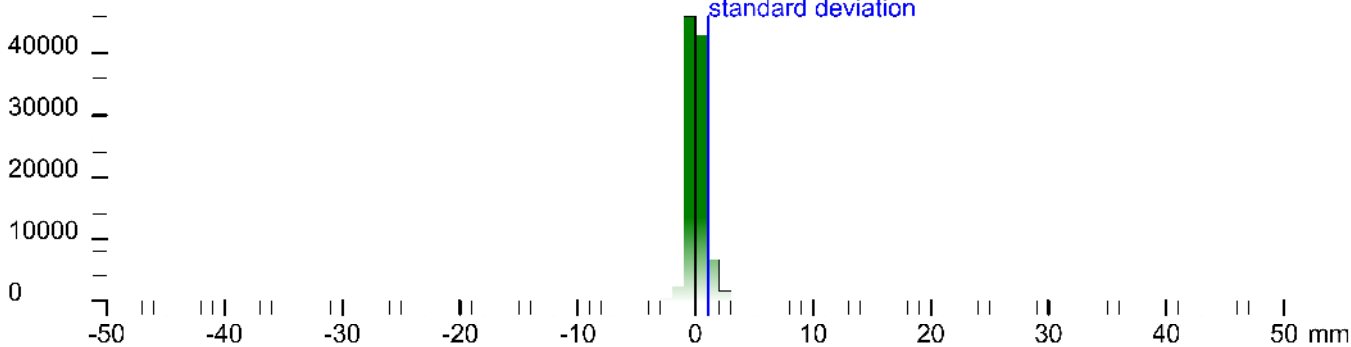
Registration matrix:

```
-0.270125 -0.962826 -0.000630 -17.5136 m  
0.962826 -0.270124 -0.000312 -2.1612 m  
0.000130 -0.000691 1.000000 0.8927 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 1.1 mm

Deviation histogram

Points



Scan '101'

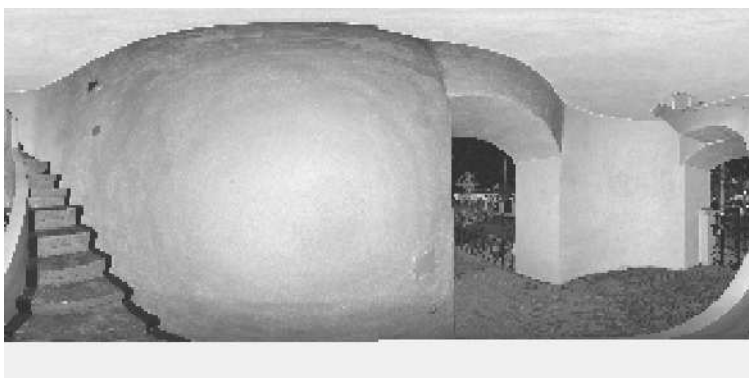
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: full 100% scan of the 140m x 10m tunnel '101' with 'Z+F IMAGER 5016' in 'point-to-point' registration mode. Serial: 22744100. Scan resolution: 0.25mm (x) x 0.25mm (y) x 0.25mm (z).  
Sensor  
sensors: 3096 'barometric transition rotation'  
Barometer: 0.999443 bar / 15.532 m  
nav translation: 0.5517 m 19.7895 m 1' 4.7109 m accuracies: 12.0912 m 2.0912 m 0.0000 m  
nav rotation: 0.0000 0.0000 2/0.7221 accuracies: 0.0000 0.0000 15.0000  
upside-down: no  
Initial pre position: (0/door)  
0.013 -1.000 0.000 -5.578  
1.000 0.013 0.000 -39.316  
0.000 0.000 1.000 -67.001  
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



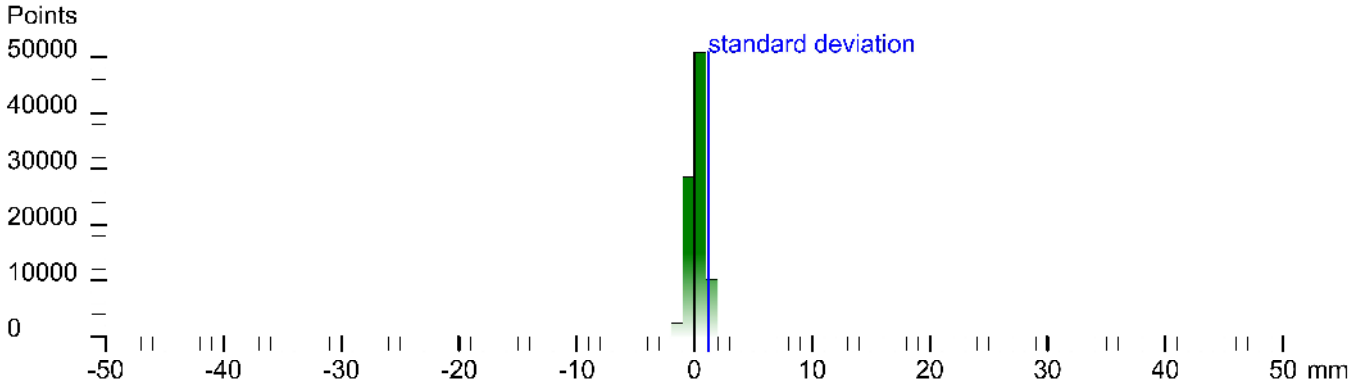
Scan position '102'

Scan position is member of group(s):
Status registration '[102h] registered with cloud to cloud'
Registration matrix:

```
-0.616184 -0.787602 -0.000367 -18.1382 m
0.787603 -0.616184 -0.000471 -1.9061 m
0.000144 -0.000579 1.000000 1.6124 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 1.2 mm

Deviation histogram



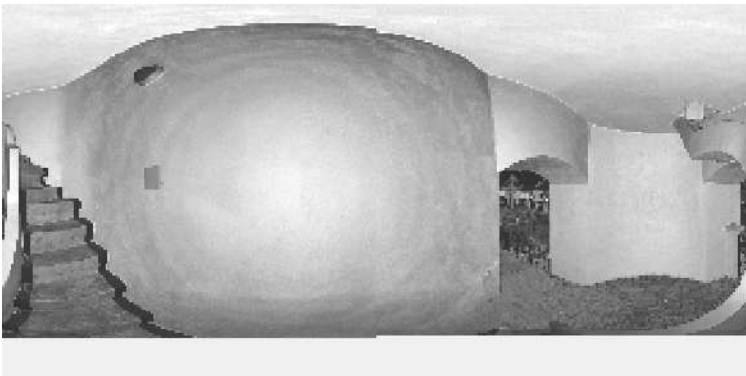
Scan '102'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

Sensor
sensors: 3096 *barome or transition rotation*
Barometer: 0.999261 bar / 17.115 in
nav translation: -1.2818 m 1.3088 m 116.0096 m accuracies: 0.0286 m 0.0286 m 0.0002 m
nav rotation: 0.0000 0.0000 256.7288 accuracies: 0.0000 0.0000 16.0000
upside-down: no
Initial pos position (Girdoor)
-3.518 -0.836 0.003 11.296
0.636 -0.549 0.000 -36.307
0.000 0.000 1.000 -65.708
0.000 0.000 0.000 1.000

Level system info: dynamic compensator available.



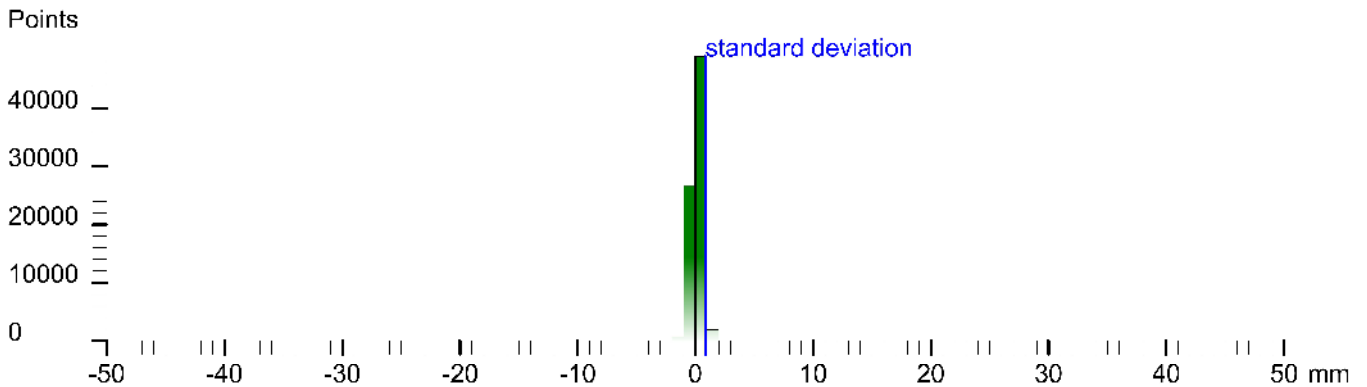
Scan position '103'

Scan position is member of group(s):
Status registration '[102h] registered with cloud to cloud'
Registration matrix:

-0.935699 -0.352798 -0.000397 -19.0605 m
0.352798 -0.935699 -0.000164 -1.9589 m
-0.000315 -0.000293 1.000000 2.5617 m
0.000000 0.000000 0.000000 1.0000

Result registration cloud to cloud standard deviation:0.8 mm

Deviation histogram



Scan '103'

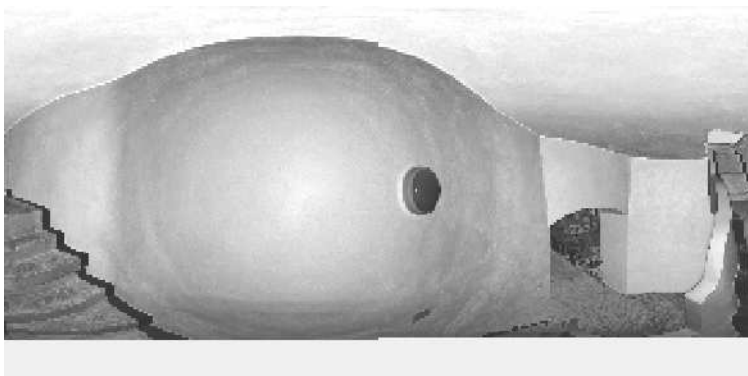
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

Scan ID: 114082103 - File: 114082103 - Group: 103 - Pos: 103 - Time: 2023-06-14 11:15:11 - Status: Success - Type: Point Cloud - Resolution: 1.000000 - Field of View: 127.46 - FOV: 127.46 - FOV: 127.46

Sensor: 3096 (barometric transition rotation)
Barometer: 0.999164 bar / 17.935 m
nav translation: -2.7927 m / -0.3890 m / 7.0018 m accuracies: 0.5210 m / 0.5210 m / 0.0000 m
nav rotation: 0.0000 0.0000 2.075286 accuracies: 0.0000 0.0000 15.0000
upside-down: no
Initial position (Girdoor):
-3.887 -0.162 0.000 11.563
0.482 -0.887 0.000 -38.096
0.000 0.000 1.000 -64.710
0.000 0.000 0.000 1.000

Level system info: dynamic compensator available.



Scan position '104'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

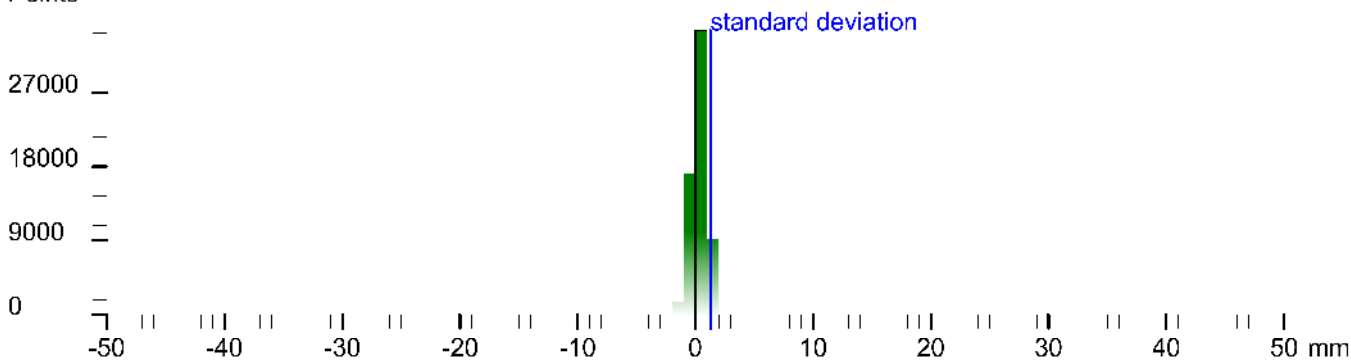
Registration matrix:

```
-0.944357  0.328923  -0.000840  -19.5020 m
-0.328922  -0.944358  -0.000265  -2.3333 m
-0.000881  0.000026  1.000000   3.5231 m
0.000000  0.000000  0.000000   1.0000
```

Result registration cloud to cloud standard deviation: 1.3 mm

Deviation histogram

Points



Scan '104'

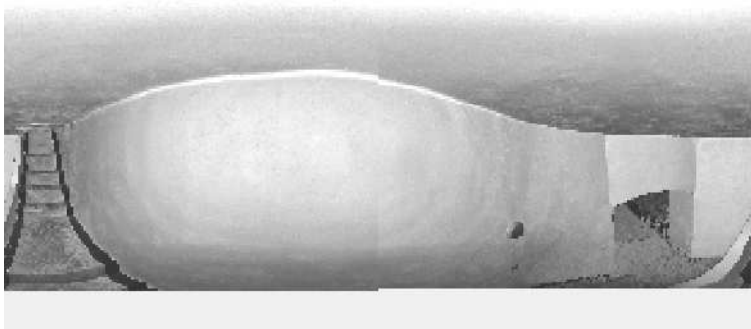
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Scan on name: '104' scan id: '104' scan type: '104' scan date: '2024-01-18' scan time: '12:40:18' scan resolution: 'High' scan quality: 'Normal'
Sensor
sensors: 3096 *barome or transition rotation*
Barometer: 0.998950 bar ~19.73 m
nav translation: -5.3075 m -2.0168 m 1 8.2428 m accuracies: 8.1003 m 8.1003 m 0.0000 m
nav rotation: 0.0000 0.0000 64.3252 accuracies: 0.0000 0.0000 15.0000
upside-down: no
Initial pos position: (Gardner)
-3.963 0 270 0.000 6.196
-0.270 -0.965 0.000 -40 / 12
0.000 0.000 1.000 -63.468
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '105'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

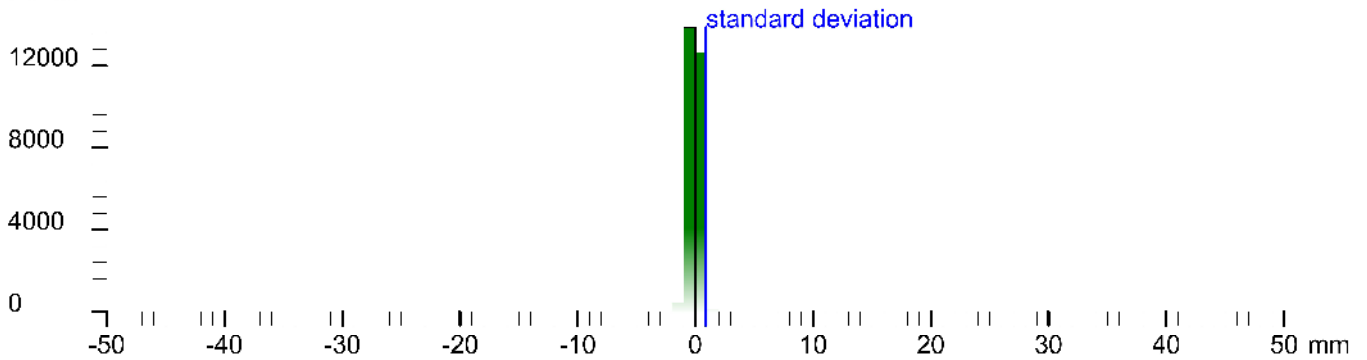
Registration matrix:

```
0.569946 -0.819993 -0.052662 -19.3620 m
-0.820350 -0.571501 0.020367 -4.6075 m
-0.046797 0.031593 -0.998404 3.7726 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:0.9 mm

Deviation histogram

Points



Scan '105'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Scan comment: null
Sensor
sensors: 3096 *barometric transition rotation*
Barometer: 0.998635 bar /22.389 m
nav translation: 0.7137 m 5.3401 m 121.7987 m accuracies: 7.8926 m 7.8926 m 3.0010 m
nav rotation: 0.0000 0.0000 0.0000 353.5239 accuracies: 0.0000 0.0000 127.1795
upside-down: yes
Initial pre position (Girdoor)
-3.997 -0.113 -0.000 6.908
-0.113 0.994 0.000 -35.372
0.000 0.000 -1.000 -59.913
0.000 0.000 0.000 1.000
```

Level system info: no information about the level system stored in the zfs header



Scan position '106'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

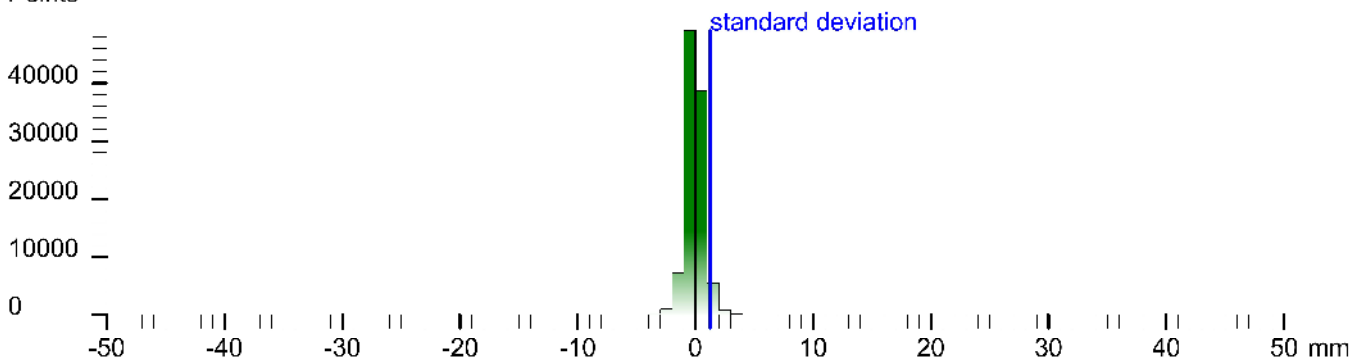
Registration matrix:

```
0.785663 0.618655 0.000032 -19.3018 m
-0.618657 0.785664 0.000105 -5.9142 m
0.000040 -0.000101 1.000000 5.8883 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 1.2 mm

Deviation histogram

Points



Scan '106'

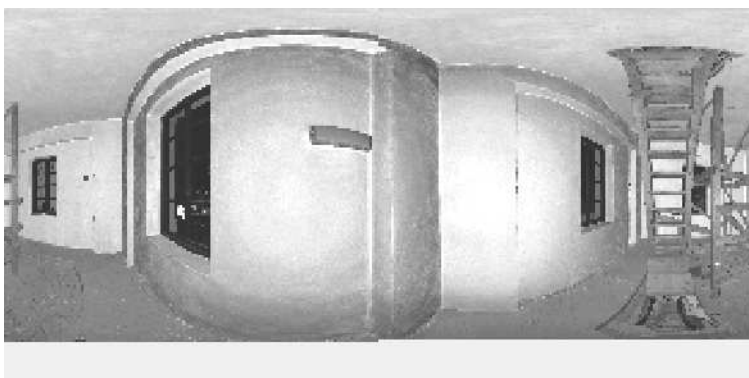
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: null  
Sensor  
sensors: 3096 *barometric transition rotation*  
Barometer: 0.998234 bar *25.768 m  
nav translation: -1.2873 m 11.0873 m 124.9072 m accuracies: 10.6858 m 10.6858 m 0.0000 m  
nav rotation: 0.0000 0.0000 63.0966 accuracies: 0.0000 0.0000 1s.0000  
upside-down: no  
Initial position: (0:door)  
0.452 0.892 0.000 5.676  
-0.892 0.452 0.000 -46.466  
0.000 0.000 1.000 -56.745  
0.000 0.000 0.000 1.000
```

Level system info: no information about the level system stored in the zfs header



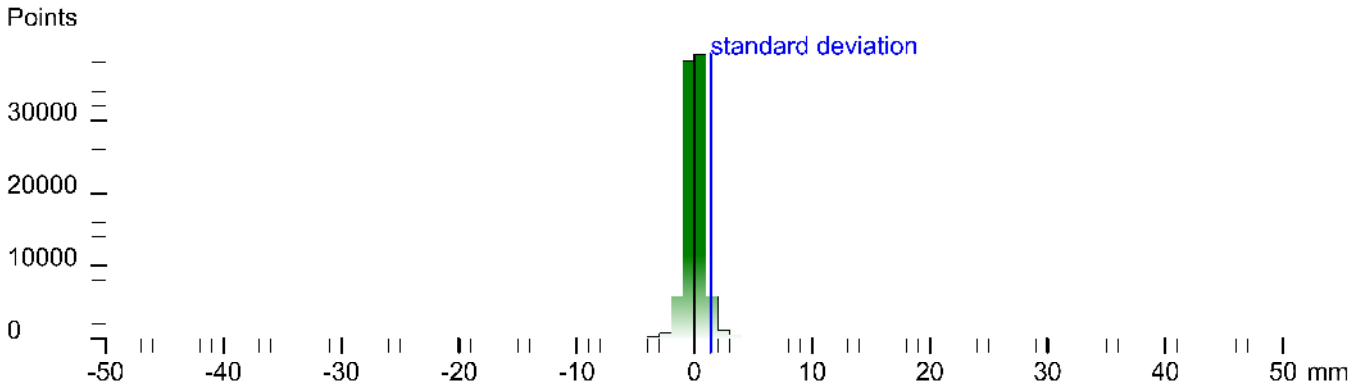
Scan position '107'

Scan position is member of group(s):
Status registration '[102h] registered with cloud to cloud'
Registration matrix:

```
0.998650 -0.051957 -0.000093 -16.4518 m
0.051956 0.998651 0.000785 -3.8814 m
0.000054 -0.000789 0.999999 5.8823 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 1.4 mm

Deviation histogram



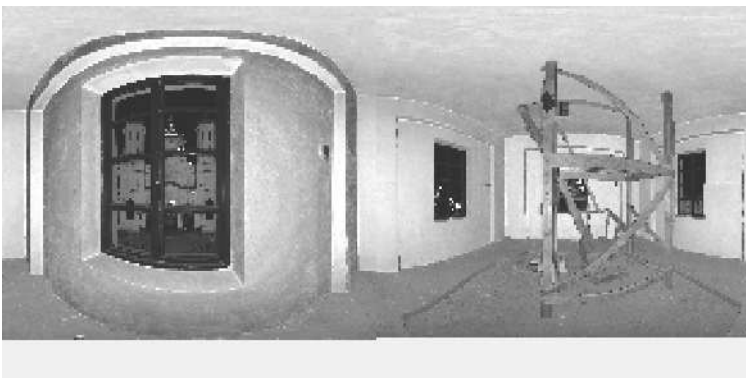
Scan '107'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Scan comment: null  
Sensor  
sensors: 3096 *barometric transition rotation*  
Barometer: 0.998087 bar / 27.007 m  
nav translation: 1.5905 m -0.5990 m 126.2065 m accuracies: 5.975 * m 5.975 * m 0.000 * m  
nav rotation: 0.0000 0.0000 9.7423 accuracies: 0.0000 0.0000 1s.0000  
upside-down: no  
Initial pre position: (Girdoor)  
0.986 0.168 0.000 7.266  
-0.168 0.986 0.000 -4.024  
0.000 0.000 1.000 -55.505  
0.000 0.000 0.000 1.000
```

Level system info: no information about the level system stored in the zfs header



Scan position '108'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

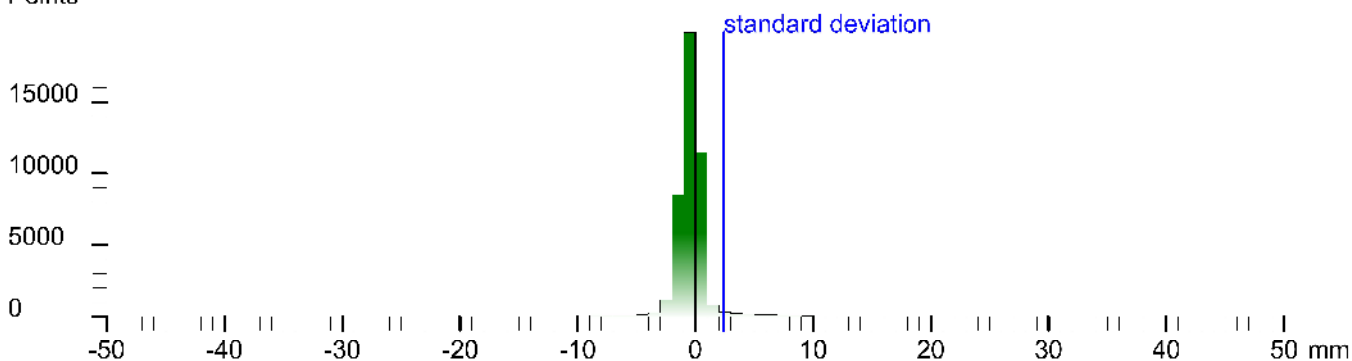
Registration matrix:

```
-0.244539 -0.969640 -0.000327 -17.1030 m  
0.969641 -0.244538 0.000621 -1.6249 m  
-0.000682 -0.000166 0.999999 5.8675 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:2.4 mm

Deviation histogram

Points



Scan '108'

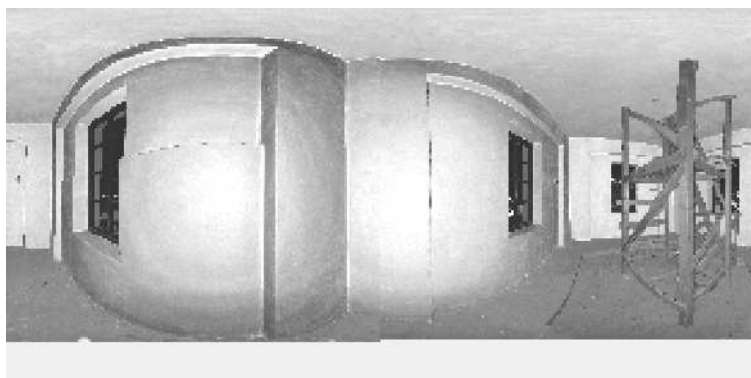
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: null  
Sensor  
sensors: 3096 *barometric transition rotation*  
Barometer: 0.997976 bar / 27.937 m  
nav translation: -1.7532 m 4.9787 m 127.5428 m accuracies: 7.7638 m 7.7638 m 0.0000 m  
nav rotation: 0.0000 0.0000 260.6959 accuracies: 0.0000 0.0000 1s.0000  
upside-down: no  
Initial pre position: (0irdoor)  
0.162 -0.987 0.000 5.513  
0.987 -0.162 0.000 -42.046  
0.000 0.000 1.000 -54.168  
0.000 0.000 0.000 1.000
```

Level system info: no information about the level system stored in the zfs header



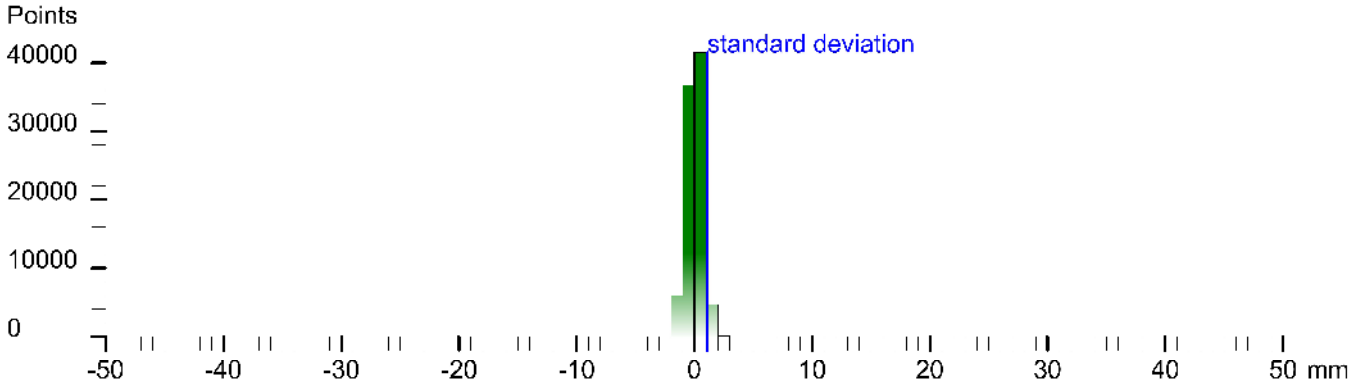
Scan position '109'

Scan position is member of group(s):
Status registration '[102h] registered with cloud to cloud'
Registration matrix:

```
-0.937005  0.349320 -0.000352 -20.1430 m  
-0.349319 -0.937004  0.001343  -1.8367 m  
0.000139  0.001381  0.999998   5.8812 m  
0.000000  0.000000  0.000000   1.0000
```

Result registration cloud to cloud standard deviation: 1.1 mm

Deviation histogram



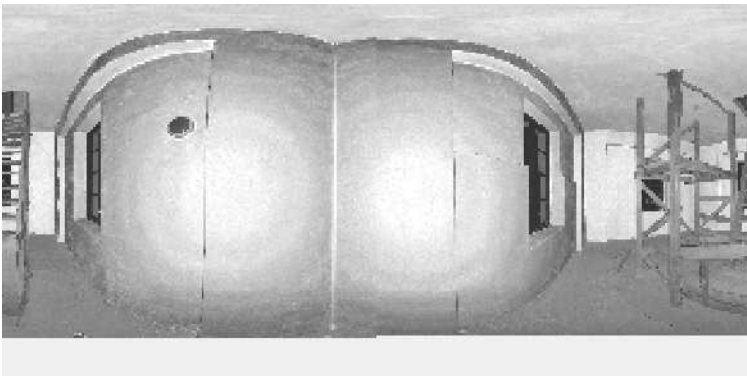
Scan '109'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
Scan resolution 'High' quality 'Normal'

Metadata Value comment operator

```
Scan comment: null  
Sensor  
sensors: 3096 *barometer transition rotation*  
Barometer: 0.997989 bar * 27.825 m  
nav translation: -1.1780 m -0.2349 m 127.3028 m accuracies: 5.7045 m 5.7045 m 0.0000 m  
nav rotation: 0.0000 0.0000 0.0000 // // // 0.74 accuracies: 0.0000 0.0000 1s.0000  
upside-down: no  
Initial pose position: (Girdoor)  
-0.998 0 0 0 0.000 4.335  
-0.040 -0.999 0.000 -42.28  
0.000 0.000 1.000 -54.408  
0.000 0.000 0.000 1.000
```

Level system info: no information about the level system stored in the zfs header



Scan position '11'

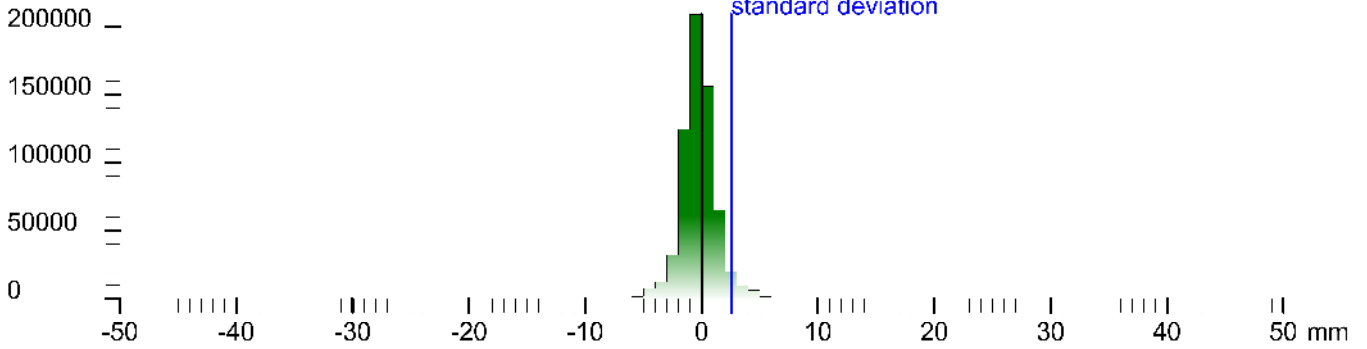
Scan position is member of group(s):
Status registration '[102h] registered with cloud to cloud'
Registration matrix:

```
0.905460 -0.424436 0.000023 18.3388 m  
0.424435 0.905460 -0.000006 1.4752 m  
-0.000018 0.000015 0.999999 0.8974 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 2.5 mm

Deviation histogram

Points



Scan '11'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
Scan resolution 'High' quality 'Normal'

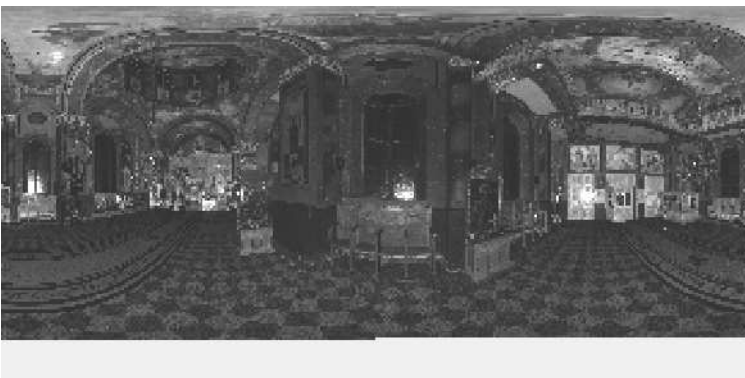
Metadata Value

comment	Value
operator	

Scan comment: null
Sensor

```
sensors: 3096 *barometric rotation*  
Barometer: 0.992083 bar / 77.727 m  
nav translation: 1.6365 m -1.4160 m 177.2567 m accuracies: 7.5172 m 7.5172 m 0.0000 m  
nav rotation: 0.0000 0.0000 0.0000 0.5393956 accuracies: 0.0000 0.0000 1s.0000  
upside-down: no  
Initial pre position (Girdoor)  
0.930 -0.352 0.000 -1.938  
0.352 0.930 0.000 -4.396  
0.000 0.000 1.000 -3.520  
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '110'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

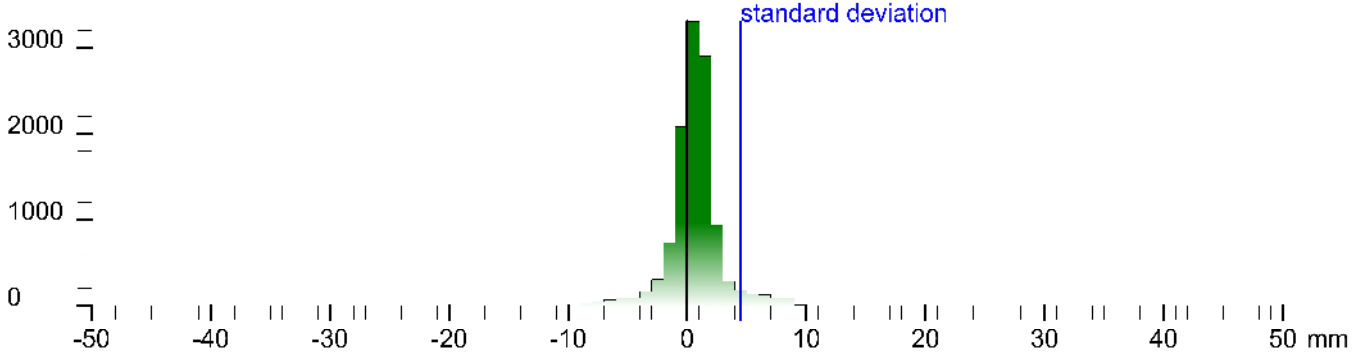
Registration matrix:

```
-0.974443 -0.224638 -0.000355 55.1033 m
0.224638 -0.974443 0.000036 52.8873 m
-0.000355 -0.000044 1.000000 11.0161 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:4.5 mm

Deviation histogram

Points



Scan '110'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: full 1908x1033 mm scan 1:46:11.0 seconds 110° pitch 8x.8° tilt 5x.8° yaw 1° spin/rot. date: 2024-11-22 14:18:54 scan 1:46:11.0 seconds 1908x1033 mm scan resolution: 110° pitch 8x.8° tilt 5x.8° yaw 1° spin/rot. date: 2024-11-22 14:18:54  
Sensor  
sensors: 3100 *barometer/transition rotation/gps  
Barometer: 0.998168 bar / 28.317 m  
nav translation: 0.0000 m 0.0000 m 126.11° 91 m accuracies: 5.1000 m 5.1000 m 0.0000 m  
nav rotation: 0.0000 0.0000 *91.9364 accuracies: 0.0000 0.0000 1s.0000  
upside-down: no  
GPS lat: 44.9438+0 long: 26 029936 satellites: 9 height: 104.3m hhdop: 1.1 vdcpr: 1.5m hacc: 0.3-m vacc: 4.5 flags: G3 'stand alone 3D solution'  
ortho: 1977168.745 m east: 423469.411 m zone: 35T  
Initial pre position (3-coo. tocoor):  
-0.978 -0.207 0.000 51.876  
0.207 -0.978 0.000 -8.572  
0.000 0.000 1.000 -55.593  
0.000 0.000 0.000 1.000
```

Level system info: no information about the level system stored in the zfs header



Scan position '111'

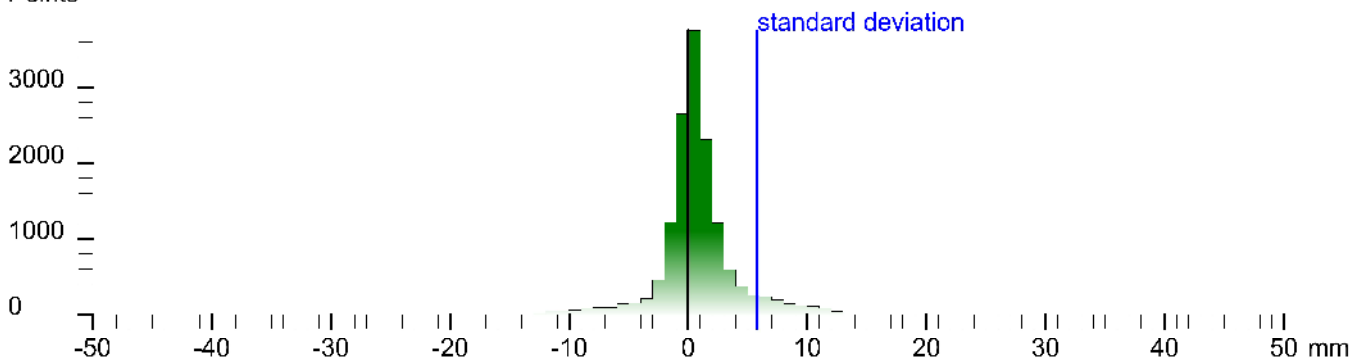
Scan position is member of group(s):
Status registration '[102h] registered with cloud to cloud'
Registration matrix:

```
-0.842889 -0.538089 -0.000022 58.7552 m  
0.538089 -0.842889 -0.000025 37.8413 m  
-0.000005 -0.000033 1.000000 11.0423 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:5.8 mm

Deviation histogram

Points



Scan '111'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: null  
Sensor  
sensors: 3100 *barome or transition rotation gps  
Barometer: 0.998225 bar / 25.84 m  
nav translation: -11.0087 m / -4.5679 m 125.2779 m accuracies: 11.5309 m 14.5309 m 0.0000 m  
nav rotation: 0.0000 0.0000 204.0658 accuracies: 0.0000 0.0000 15.0000  
upside-down: no  
GPS lat:44.943672 long:26.029901 satellites: 11 height:197.7m hdop:0.8 vdop:1.2m hacc:2.8m vacc:4.1 tags:G3 'stand alone 3D solution'  
north:4977150.747 m east:423473.581 m zone:35T  
Initial pre position (3-coo. tocoor)  
-0.910 -0.416 0.000 55.791  
0.416 -0.910 0.000 -2.743  
0.000 0.000 1.000 -56.437  
0.000 0.000 0.000 1.000
```

Level system info: no information about the level system stored in the zfs header



Scan position '112'

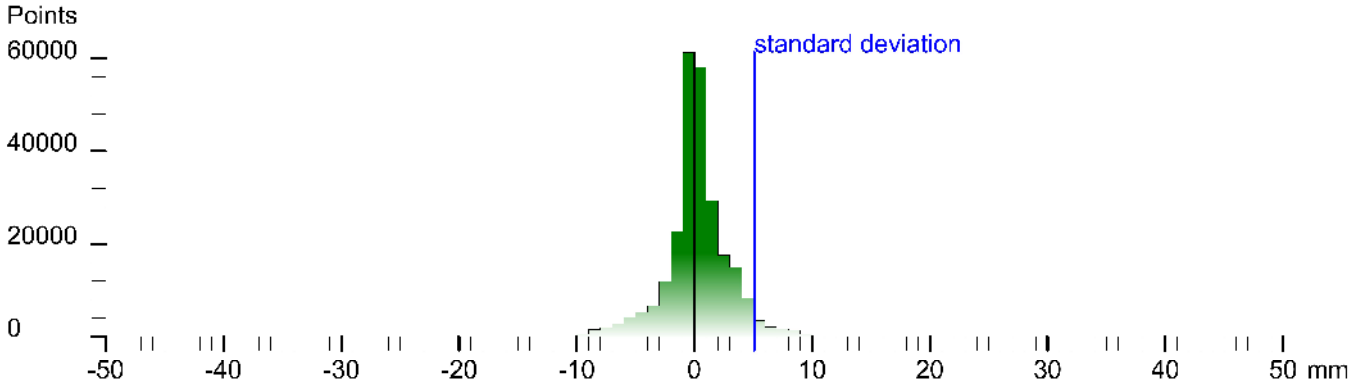
Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```

0.993993 -0.109452 -0.000191 13.2319 m
0.109452 0.993993 0.000748 28.4330 m
0.000108 -0.000764 1.000000 0.8695 m
0.000000 0.000000 0.000000 1.0000
    
```

Result registration cloud to cloud standard deviation:5.1 mm

Deviation histogram



Scan '112'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```

Scan comment: null
Sensor
sensors: 3100 *barometer
Barometer: 0.999203 bar *17.603 m
nav translation: 0.0000 m 0.0000 m 117.1713 m accuracies: 5.1000 m 5.1000 m 0.0001 m
nav rotation: 0.0000 0.0000 0.0000
upside-down: no
GPS lat:44.943692 long:26.029396 satellites:7 height:185.4m hdop:*.6 vdcpx:6.7m hacc:6.6-m vacc:22.0 flags:G3 's'anc sbno 3D solution'
north:4977112.710 m east:423426.527 m zcra:35T
Initial pre position (3-coor):
0.997 -0.083 0.000 6.744
0.053 0.997 0.000 -0.488
0.000 0.000 1.000 -64.510
0.000 0.000 0.000 1.000
    
```

Level system info: no information about the level system stored in the zfs header



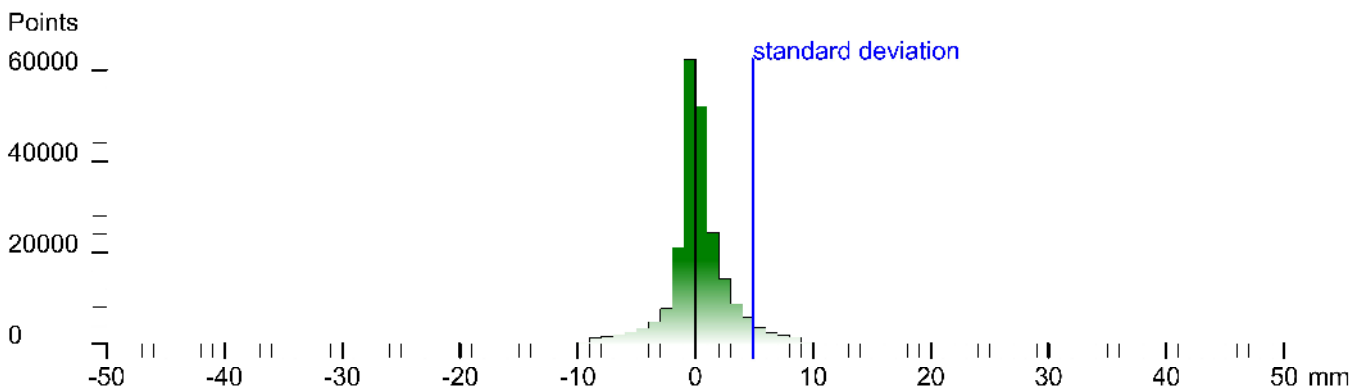
Scan position '113'

Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```
0.388717 0.921358 -0.000346 26.2856 m
-0.921358 0.388717 0.000607 33.9035 m
0.000694 0.000083 1.000000 0.4678 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:4.9 mm

Deviation histogram



Scan '113'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: null
Sensor
sensors: 3100 *barome or transtion rotation gps
Barometer: 0.999411 bar 115.855 m
nav translation: 10.8798 m 1.298° m 1 5.8791 m accuracies: 10.7012 m 3.7012 m 0.0000 m
nav rotation: 0.0000 0.0000 66.30/3 accuracies: 0.0000 0.0000 1s.0000
upside-down: no
GPS lat:44.943653 long:26.029535 satellites:5 height:194.2m hddo:2.2 vddcp:4.0m hacc: 0.0m vacc:16.0 tags:G3 *stand alone 3D solution
north:1977118.059 m east:423437.592 m zone:35T
Initial pre position (3co. tcoor):
0.370 0.929 0.000 19.774
-0.929 0.370 0.000 -3. 89
0.000 0.000 1.000 -65.833
0.000 0.000 0.000 1.000
```

Level system info: no information about the level system stored in the zfs header



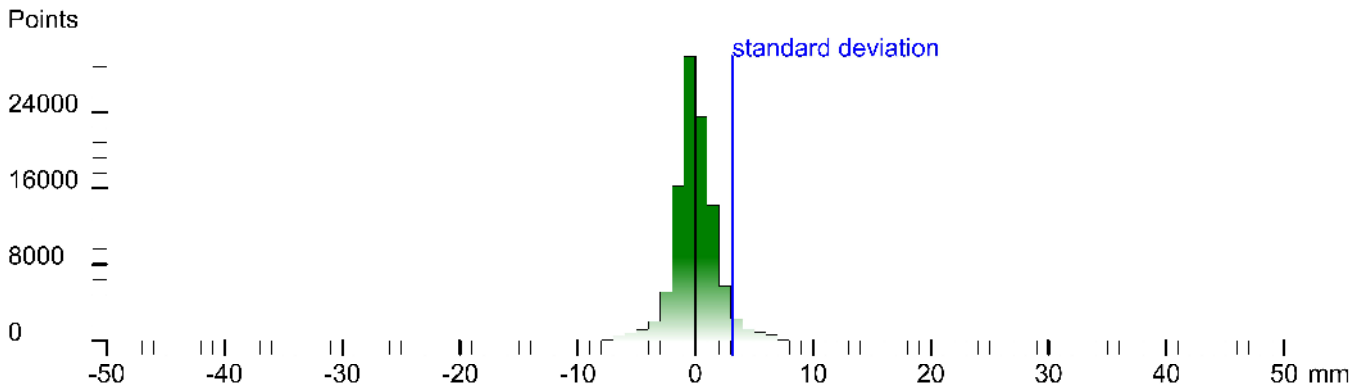
Scan position '114'

Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```
-0.886946 -0.461860 0.003845 -19.3726 m
0.461824 -0.886939 -0.007758 -6.0720 m
0.006993 -0.005106 0.999961 10.0817 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:3.1 mm

Deviation histogram



Scan '114'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata Value

comment
operator

```
Scan position: '114' parent: '114' group: '114' type: 'Z+F IMAGER 5016' serial: '5016-0100' firmware: '9.0.3.6562-0' resolution: 'High' quality: 'Normal'
Sensor
sensors: 3096 *barometer (transition rotation)
Barometer: 0.998372 bar / 24.804 m
nav translation: -57.0868 m / -70.9509 m / 21.0067 m accuracies: 51.5619 m 51.5619 m 0.0000 m
nav rotation: 0.0000 0.0000 228.415 / accuracies: 0.0000 0.0000 1s.0000
upside-down: no
Initial pre position: (0 indoor)
-3.66 / -0.746 0.000 -87.973
0.748 -0.664 0.000 -80.166
0.000 0.000 1.000 -57.105
0.000 0.000 0.000 1.000
```

Level system info: no information about the level system stored in the zfs header



Scan position '115'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

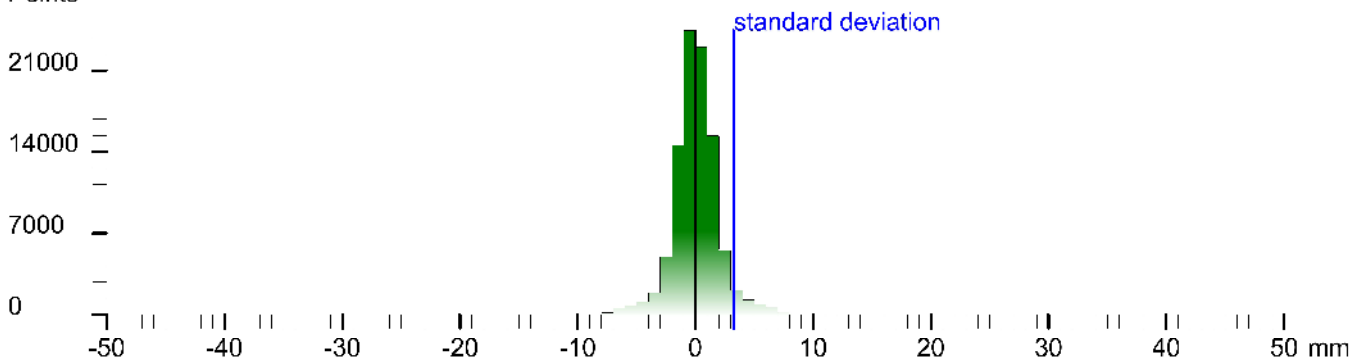
Registration matrix:

```
0.994776 0.102036 0.003293 -19.7901 m
-0.102009 0.994757 -0.007505 -1.4383 m
-0.004042 0.007130 0.999965 10.1199 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:3.3 mm

Deviation histogram

Points



Scan '115'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Scan comment: null
Sensor
sensors: 3096 *barometric (transition rotation)
Barometer: 0.998438 bar *24.048 m
nav translation: 2.4732 m 0.8111 m 123.7052 m accuracies: 6.4227 m 6.4227 m 0.0000 m
nav rotation: 0.0000 0.0000 0.12886 accuracies: 0.0000 0.0000 0.0000
upside-down: no
Initial pre position: (0/door)
0.858 0.518 0.000 -35.500
-0.518 0.858 0.000 -79.302
0.000 0.000 1.000 -58.007
0.000 0.000 0.000 1.000
```

Level system info: no information about the level system stored in the zfs header



Scan position '116'

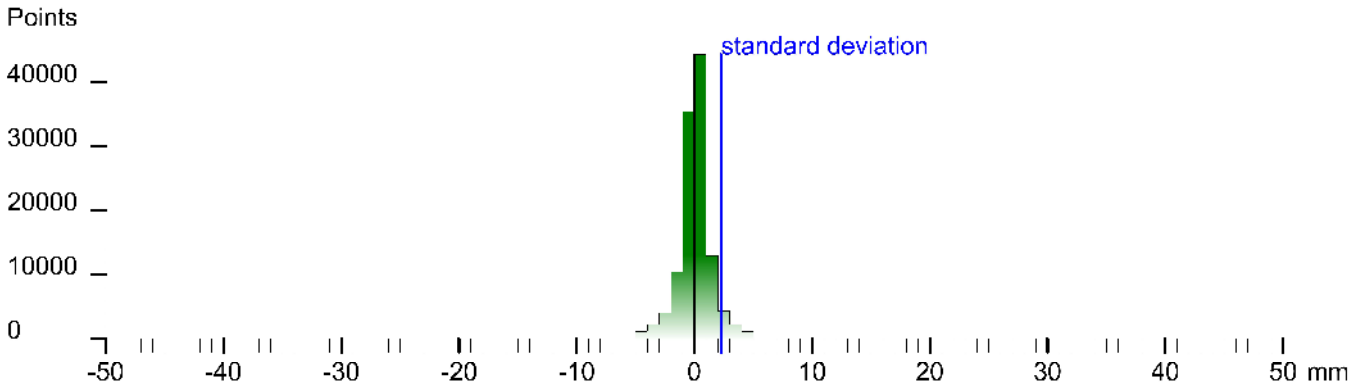
Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```

0.998524 -0.054329 -0.001668 -19.6731 m
0.054299 0.998426 -0.014178 -1.3669 m
0.002435 0.014067 0.999897 12.4825 m
0.000000 0.000000 0.000000 1.0000
  
```

Result registration cloud to cloud standard deviation: 2.3 mm

Deviation histogram



Scan '116'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```

Sensor
sensors: 3096 *barome or transition rotation*
Barometer: 0.998124 bar *20.80 m
nav translation: 4.3102 m 0.2036 m 12*.07*0 m accuracies: 7.27*6 m 7.27*6 m 3.0000 m
nav rotation: 0.0000 0.0000 334.6129 accuracies: 0.0000 0.0000 101.***
upside-down: no
Initial pre position: (0/door)
0.996 -0.094 0.000 -31.190
0.094 0.996 0.000 -79.148
0.000 0.000 1.000 -57.041
0.000 0.000 0.000 1.000
  
```

Level system info: no information about the level system stored in the zfs header



Scan position '117'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

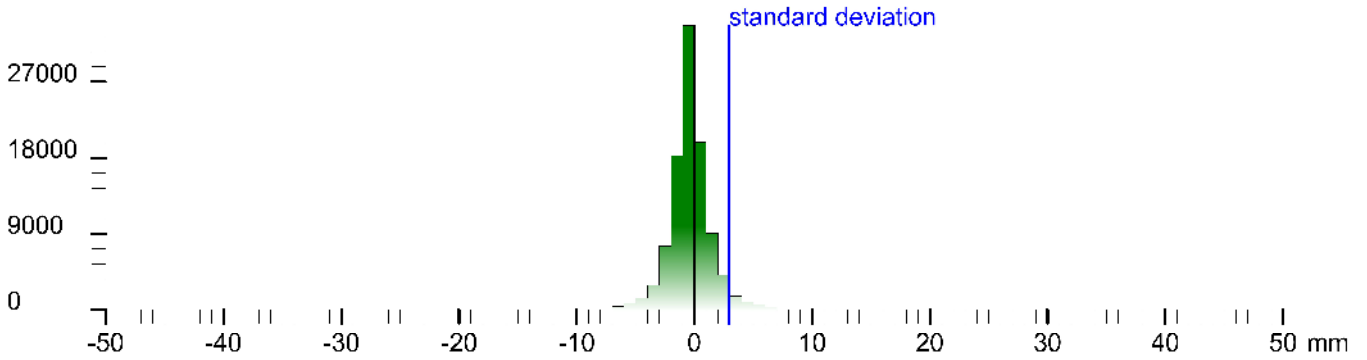
Registration matrix:

```
-0.711616  0.702562  0.003682 -17.9888 m
-0.702565 -0.711579 -0.007850  -3.3875 m
-0.002894 -0.008172  0.999961  10.0867 m
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation:2.9 mm

Deviation histogram

Points



Scan '117'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Scan comment: '117'
Sensor
sensors: 3096 *barome or transition rotation*
Barometer: 0.998282 bar / 25.356 m
nav translation: -2.8757 m -5.1942 m 124.4970 m accuracies: 8.0782 m 8.0782 m 0.0000 m
nav rotation: 0.0000 0.0000 0.423098 accuracies: 0.0000 0.0000 1s.0000
upside-down: no
Initial pre position: (Girdoor)
-3.793 0.609 0.000 -84.365
-0.609 -0.785 0.000 -84.342
0.000 0.000 1.000 -57.215
0.000 0.000 0.000 1.000
```

Level system info: no information about the level system stored in the zfs header



Scan position '118'

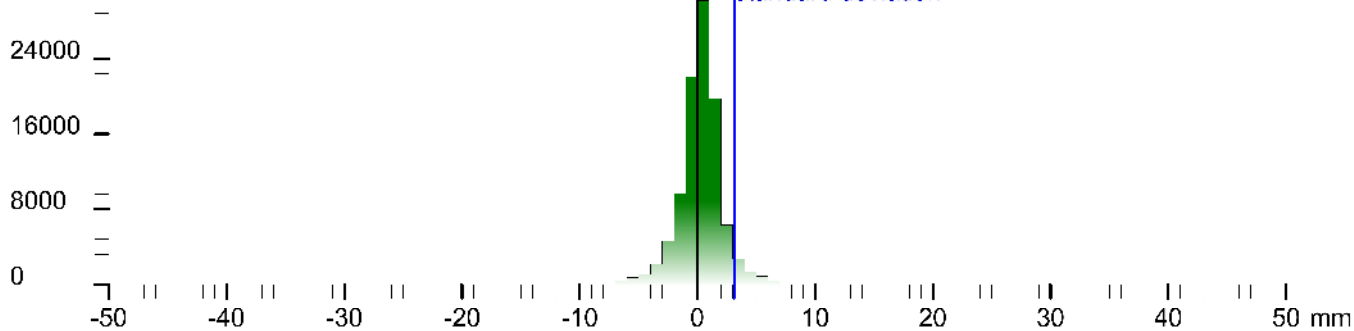
Scan position is member of group(s):
Status registration '[102h] registered with cloud to cloud'
Registration matrix:

```
0.508912  0.860817  -0.002272 -17.0776 m
-0.860820  0.508905  -0.002851  -4.5288 m
-0.001299  0.003406  0.999993  12.7661 m
0.000000  0.000000  0.000000   1.0000
```

Result registration cloud to cloud standard deviation: 3.1 mm

Deviation histogram

Points



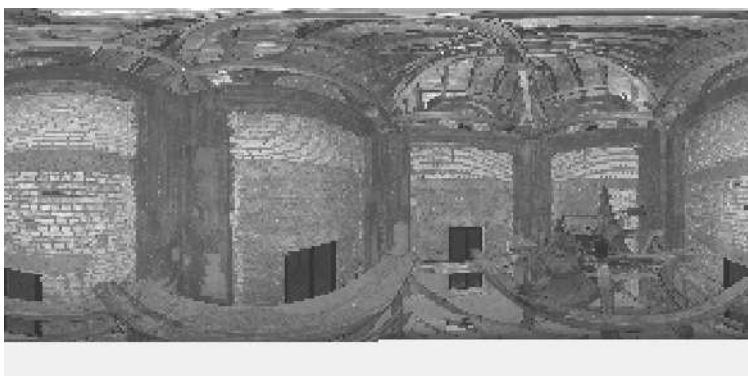
Scan '118'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan position is member of group(s): [102h] registered with cloud to cloud
Sensor
sensors: 3096 "barometric transition rotation"
Barometer: 0.998033 bar / 27.455 m
nav translation: 3.9330 m -4.2970 m 125.2535 m accuracies: 7.9959 m 7.9959 m 0.0001 m
nav rotation: 0.0000 0.0000 0.0000 accuracies: 0.0000 0.0000 0.0000
upside-down: no
Initial position (0 indoor)
0.515 0.857 0.000 -30.132
-0.877 0.515 0.000 -88.576
0.000 0.000 1.000 -56.461
0.000 0.000 0.000 1.000
```

Level system info: no information about the level system stored in the zfs header



Scan position '119'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

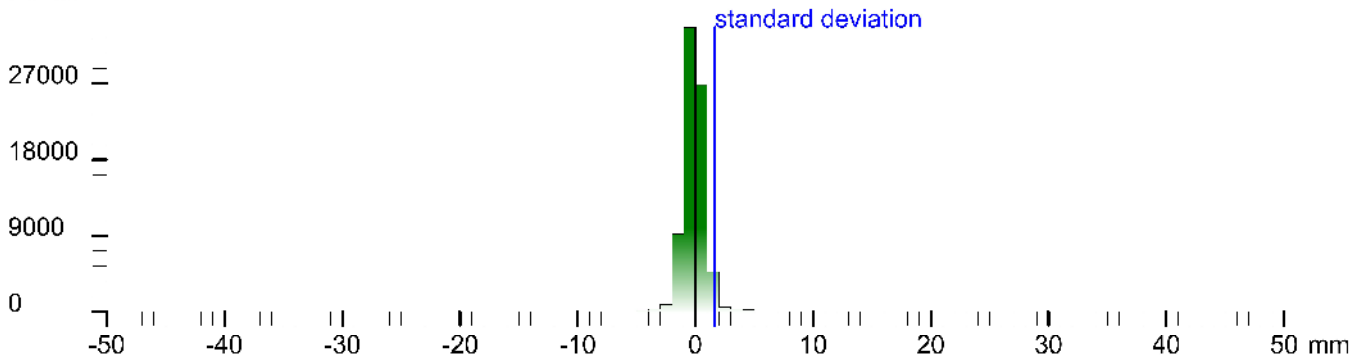
Registration matrix:

```
0.999009 -0.044516 -0.000220 -16.1118 m
0.044515 0.999008 0.001590 -3.5255 m
0.000149 -0.001598 0.999999 5.7247 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:1.6 mm

Deviation histogram

Points



Scan '119'

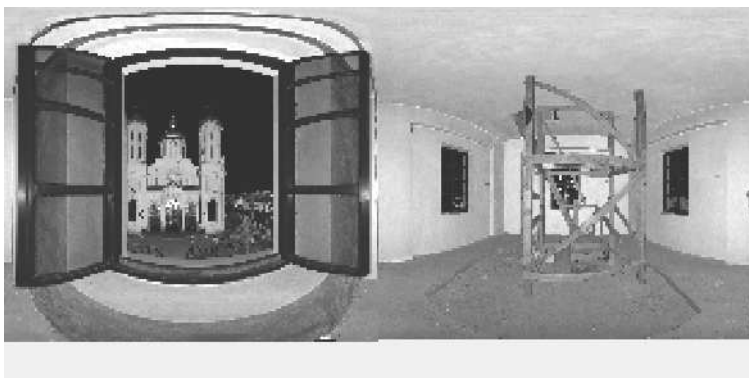
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: 'id:130848633' 'name:146' '119' 'series:119' 'pitch:8.8' 'roll:8.8' 'time:13.21' 'series:' 'Z+F' 'ip:10.10.10.10' 'start:146' 'end:146' 'file:' '119' 'file:' '119' 'dir:' '119'
Sensor
sensors: 3100 *barome or transition rotation gps
Barometer: 0.998040 bar / 19.8 °C m
nav translation: -1.3527 m -3.336 m 1 9.3493 m accuracies: 7.1757 m 7.1757 m 0.0001 m
nav rotation: 0.0000 0.0000 0.0000 / accuracies: 0.0000 0.0000 1s.0000
upside-down: no
GPS lat:44.943302 long:26.026971 satellites:3 height:195.1m hdop:3.3 vtcp:1.0m hacc: 3.2m vacc:22.0 tags:G2 'stand alone 2D solution'
north:1977110.600 nr_east:423392.585 m zone:35T
Initial pre position (0:indoor)
0.995 0.097 0.000 -31.485
-0.007 0.995 0.000 -91.312
0.000 0.000 1.000 -62.362
0.000 0.000 0.000 1.000
```

Level system info: no information about the level system stored in the zfs header



Scan position '12'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

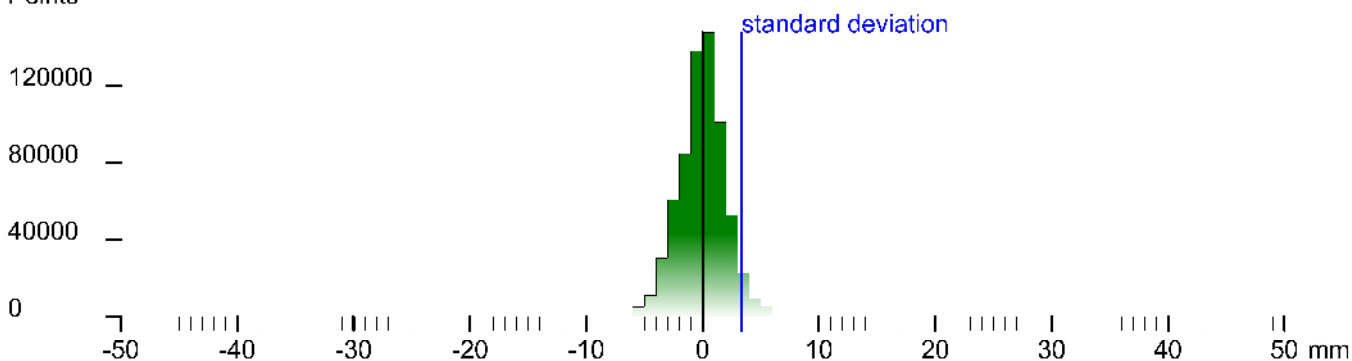
Registration matrix:

```
-0.766114 -0.642705 0.000251 21.4655 m  
0.642706 -0.766115 -0.000153 8.6329 m  
0.000289 0.000044 1.000000 0.6788 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:3.3 mm

Deviation histogram

Points



Scan '12'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata Value comment operator

```
Scan comment: '12' - name: '12' - scan: '12' - time: '12:12:12' - date: '2012-01-12' - time: '12:12:12' - date: '2012-01-12' - time: '12:12:12' - date: '2012-01-12'  
Sensor  
sensors: 3096 'barometric transition rotation'  
Barometer: 0.992119 bar 177.42 m  
nav translation: 5.1857 m -1.4188 m 177.0559 m accuracies: 8.5396 m 8.5396 m 0.0000 m  
nav rotation: 0.0000 0.0000 206.1350 accuracies: 0.0000 0.0000 15.0000  
upside-down: no  
Initial pos position (0/door)  
-3.898 -0.140 0.000 3.278  
0.440 -0.898 0.000 -16.846  
0.000 0.000 1.000 -3.771  
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



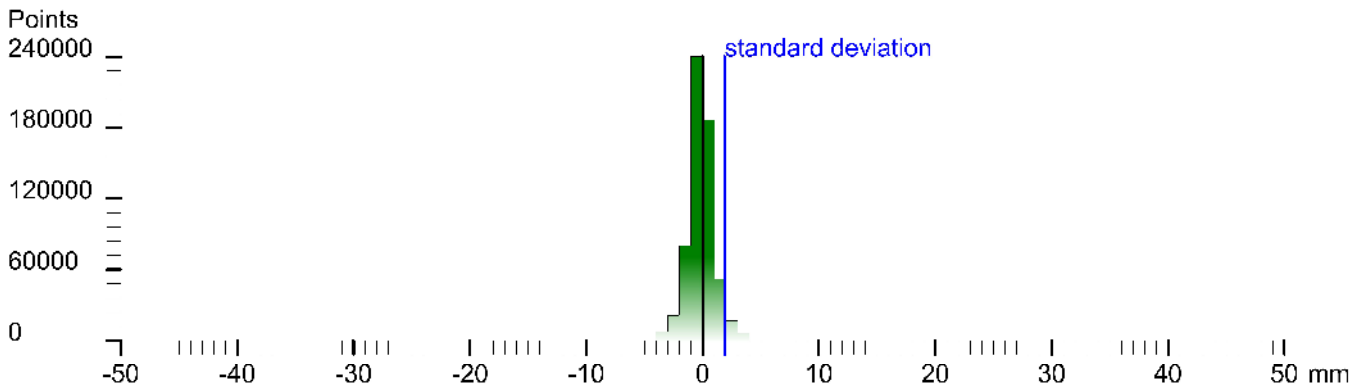
Scan position '14'

Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```
-0.980009 -0.198956 0.000335 26.1060 m
0.198957 -0.980009 0.000366 13.2916 m
0.000255 0.000426 1.000000 1.1070 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 1.9 mm

Deviation histogram



Scan '14'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: '14'
Sensor
sensors: 3096 'barometric transition rotation'
Barometer: 0.992097 bar / 77.802 m
nav translation: 0.3708 m 2.6928 m 177.0360 m accuracies: 6.5005 m 6.5005 m 0.0000 m
nav rotation: 0.0000 0.0000 -96.8738 accuracies: 0.0000 0.0000 1s.0000
upside-down: no
Initial pos position: (0 indoor)
-3.958 -0.282 0.000 5.368
0.282 -0.959 0.000 -13.968
0.000 0.000 1.000 -3.740
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



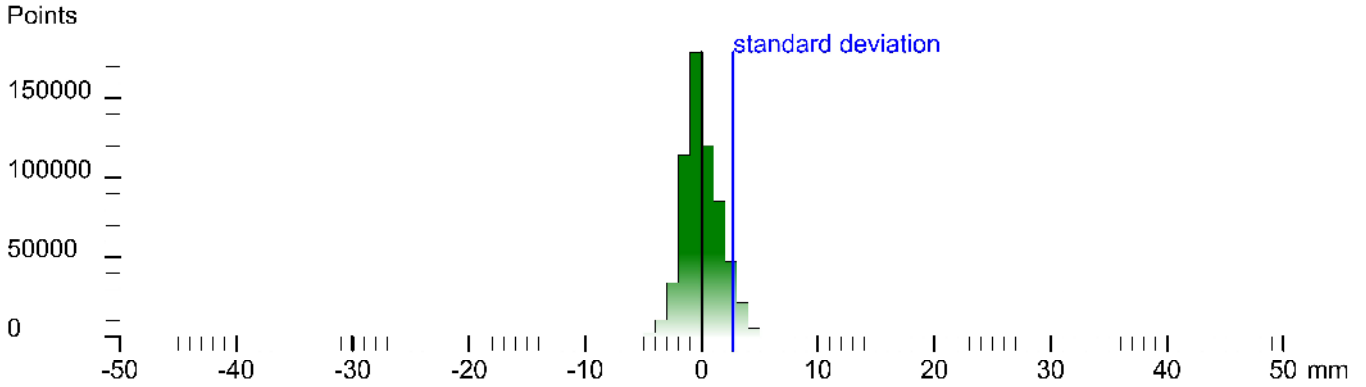
Scan position '15'

Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```
-0.355250  0.934771  0.000443  23.7257 m
-0.934772 -0.355251  0.000209  11.7159 m
 0.000353 -0.000339  1.000000  -0.2481 m
 0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation: 2.7 mm

Deviation histogram



Scan '15'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan position: '15' - name: '15' - type: 'Point' - cloud to cloud standard deviation: 2.7 mm - registration matrix: '15' - for: '15' - for: '15'
```

Sensors: 3096 'barometric rotation'
 Barometer: 0.992197 bar / 76.757 m
 nav translation: -1.5968 m 2.9173 m 176.0786 m accuracies: 0.81/8 m 0.81/8 m 0.0000 m
 nav rotation: 0.0000 0.0000 10.1436 accuracies: 0.0000 0.0000 1s.0000
 up/down: no
 Initial pre position: (Girdner)
 -3.34 / 0.839 0.000 3.772
 -0.938 -0.344 0.000 -11.080
 0.000 0.000 1.000 -4.698
 0.000 0.000 0.000 1.000

Level system info: dynamic compensator available.



Scan position '16'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

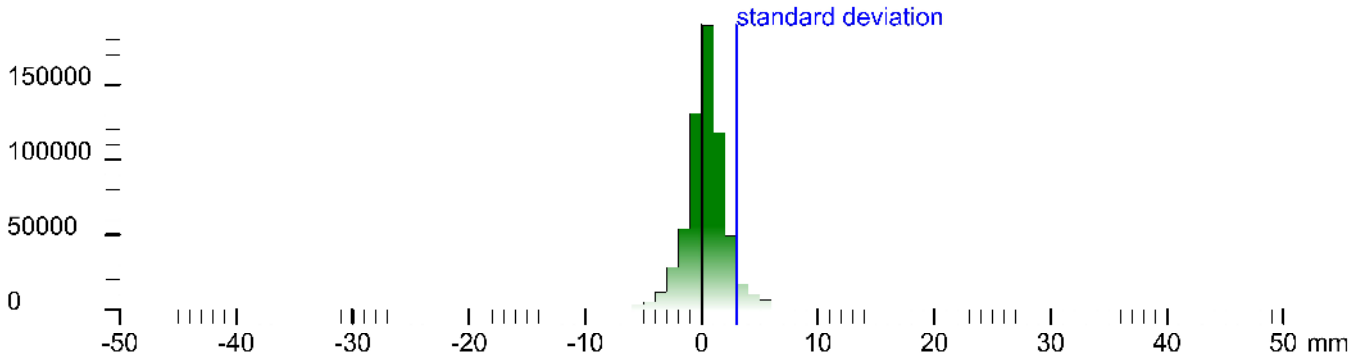
Registration matrix:

0.730188	0.683248	0.000417	27.0910 m
-0.683249	0.730187	0.000185	9.5293 m
-0.000177	-0.000420	1.000000	0.7136 m
0.000000	0.000000	0.000000	1.0000

Result registration cloud to cloud standard deviation:3.0 mm

Deviation histogram

Points



Scan '16'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

Sensor

sensors: 3096 "barometric transition rotation"
Barometer: 0.992052 bar / 77.985 m
nav translation: -2.2772 m -2.9947 m 177.0422 m accuracies: 6.9854 m 6.9854 m 0.0000 m
nav rotation: 0.0000 0.0000 42.2376 accuracies: 0.0000 0.0000 15.0000
upside-down: no
Initial pre position: (Girdoor)
0.740 0.572 0.000 1.485
-0.672 0 / 40 0.000 -13.946
0.000 0.000 1.000 -3.735
0.000 0.000 0.000 1.000

Level system info: dynamic compensator available.



Scan position '17'

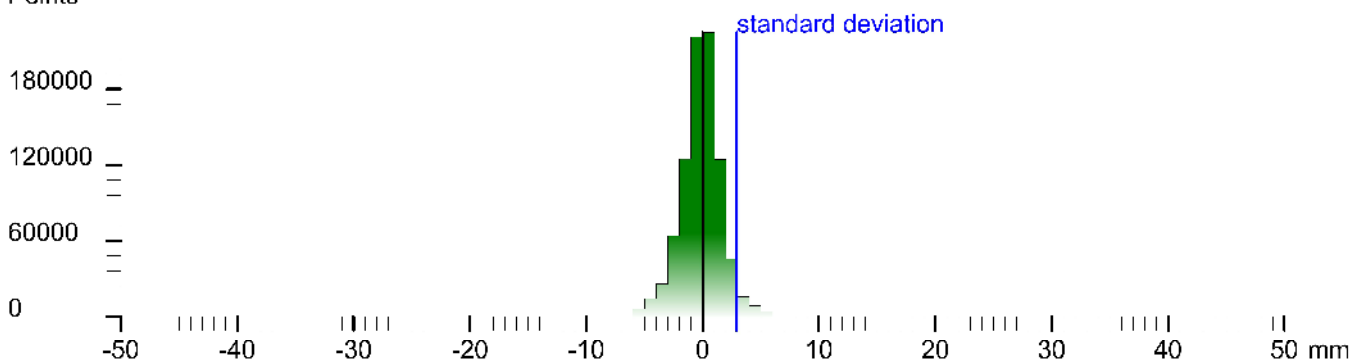
Scan position is member of group(s):
Status registration '[102h] registered with cloud to cloud'
Registration matrix:

-0.307160	0.951659	0.000376	27.9207 m
-0.951659	-0.307160	-0.000029	3.1368 m
0.000089	-0.000366	1.000000	0.7201 m
0.000000	0.000000	0.000000	1.0000

Result registration cloud to cloud standard deviation: 2.9 mm

Deviation histogram

Points



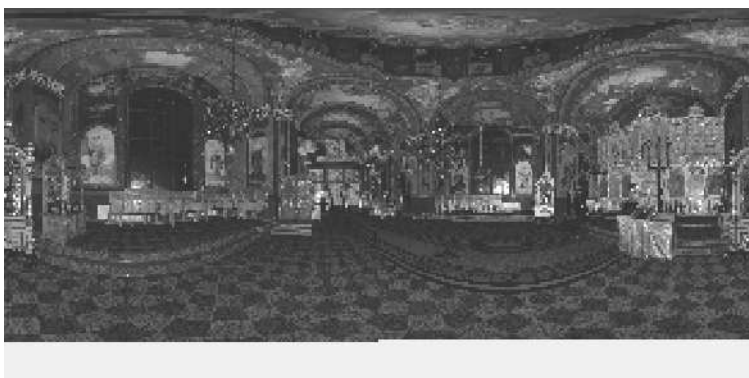
Scan '17'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

Scan on name: cal_1508042_1031 - name: 146117 - number: 17 - date: '16-08-2016 16:57:01' - spot: for data - equipment: - model: - serial: 2720000 - point: for comment: for resolution: - width: - height: - for: 11240 - for: 12044 - 1940
Sensor
sensors: 3096 *barome or transition rotation*
Barometer: 0.992016 bar * 78.23° m
nav translation: -3.6065 m 3.3830 m 178.1040 m accuracies: 0.9375 m 0.9375 m 0.0000 m
nav rotation: 0.0000 0.0000 *36.0264 accuracies: 0.0000 0.0000 15.0000
upside-down: no
Initial pose position (Girdoor)
-3.308 0.951 0.000 -2.112
-0.951 -0.309 0.000 -13.852
0.000 0.000 1.000 -2.673
0.000 0.000 0.000 1.000

Level system info: dynamic compensator available.



Scan position '18'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

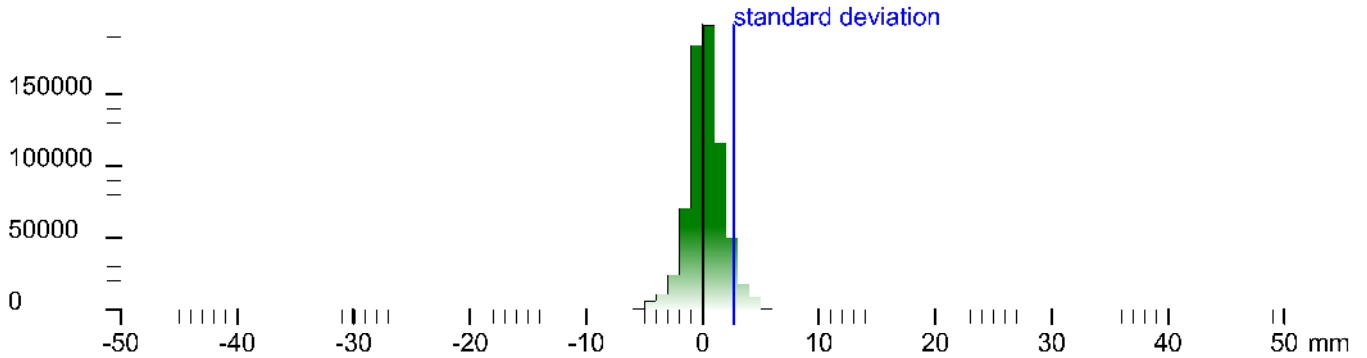
Registration matrix:

```
-0.993736 -0.111758 0.000342 24.3359 m
0.111758 -0.993736 -0.000105 1.6954 m
0.000351 -0.000065 1.000000 0.6999 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 2.6 mm

Deviation histogram

Points



Scan '18'

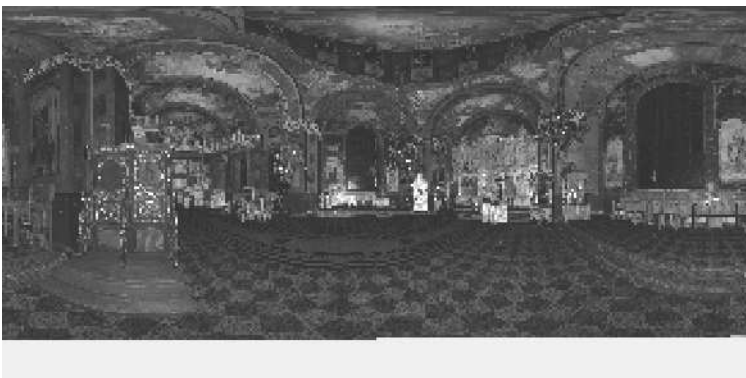
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

Scan comment: null
Sensors: 3096 *barometric transition rotation*
Barometer: 0.992017 bar / 78.283 m
nav translation: -3.7653 m 2.4623 m 177.5712 m accuracies: 0.3938 m 0.3938 m 0.0000 m
nav rotation: 0.0000 0.0000 * /s.863 / accuracies: 0.0000 0.0000 1s.0000
upside-down: no
Initial pre position: (Girdoor)
-3.987 0.072 0.000 -2.677
-3.0 / 2 -0.98 / 0.000 -11.090
0.000 0.000 1.000 -3.206
0.000 0.000 0.000 1.000

Level system info: dynamic compensator available.



Scan position '19'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

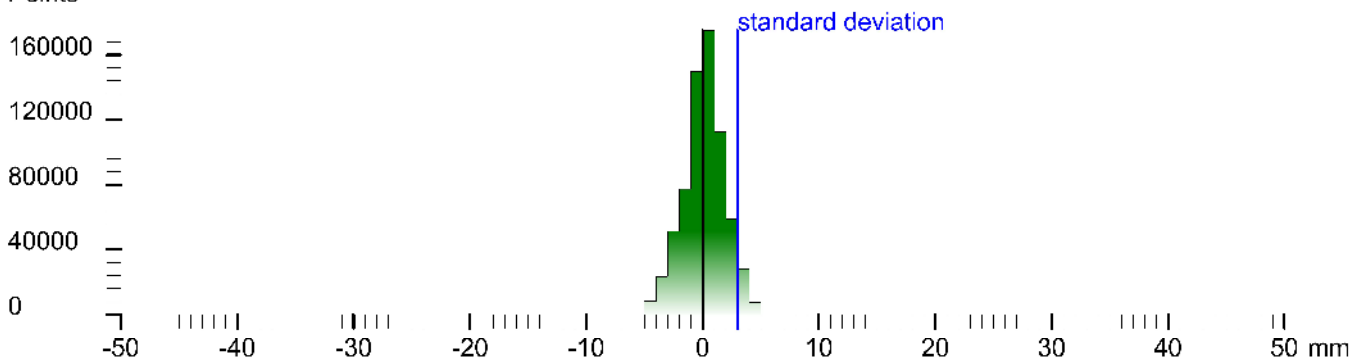
Registration matrix:

```
-0.530185  0.847882  0.000571  25.0267 m
-0.847882 -0.530185 -0.000217 -1.4038 m
0.000119 -0.000598  1.000000  1.0694 m
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation:3.0 mm

Deviation histogram

Points



Scan '19'

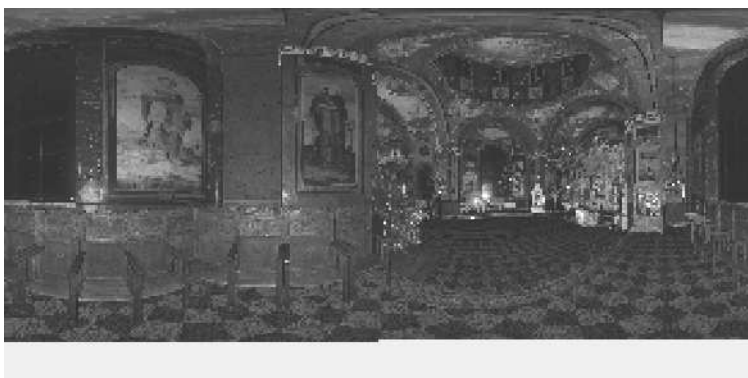
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Scan position: '19' member of group(s): '102h'
Sensor
sensors: 3096 *barometric transition rotation*
Barometer: 0.992049 bar * 78.013 m
nav translation: -2.2985 m 1.1934 m 177.0073 m accuracies: 0.387* m 0.387* m 0.0000 m
nav rotation: 0.0000 0.0000 *14.4372 accuracies: 0.0000 0.0000 1s.0000
upside-down: no
Initial pre position: (0/door)
-3.411 0.910 0.000 -5.37
-0.910 -0.414 0.000 -9.896
0.000 0.000 1.000 -3.170
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



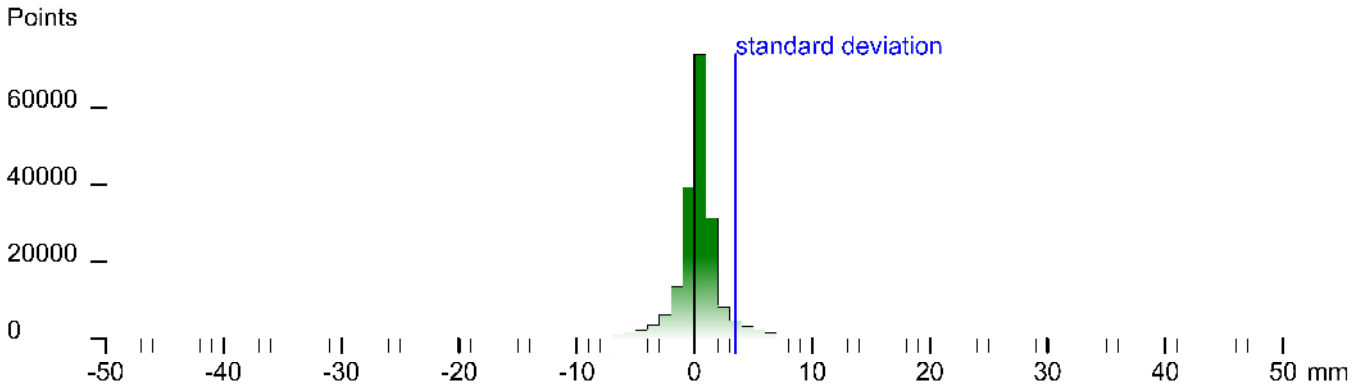
Scan position '2'

Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```
0.916576  0.399862  -0.000348  4.9377 m
-0.399862  0.916576  0.000133  0.9320 m
0.000372  0.000017  1.000000  0.7245 m
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation:3.5 mm

Deviation histogram



Scan '2'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

Scan position: 14.943359 lon; 26.029415 lat; 197.116543 m east; 423427.722 m zone:35T
 sensors: 3100 * barome or transtion rotation gps
 Barometer: 0.991618 bar ~ 81.866 m
 nav translation: 0.0000 m 0.0000 m 181.1958 m accuracies: 5.1000 m 5.1000 m 3.0000 m
 nav rotation: 0.0000 0.0000 23.1617 accuracies: 0.0000 0.0000 15.0000
 upside-down: no
 GPS lat:14.943359 lon:26.029415 satellites:3 height:197.3m hdoop:5.2 vdcop:1.0m hacc:9.4 m vacc:21.0 flags:G2 's are sbrno 2D solution'
 north:1977116.543 m east:423427.722 m zone:35T
 Initial pre position (0:indoor)
 0.939 0.345 0.000 0.000
 -0.345 0.939 0.000 0.000
 0.000 0.000 1.000 0.479
 0.000 0.000 0.000 1.000

Level system info: dynamic compensator available.



Scan position '20'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

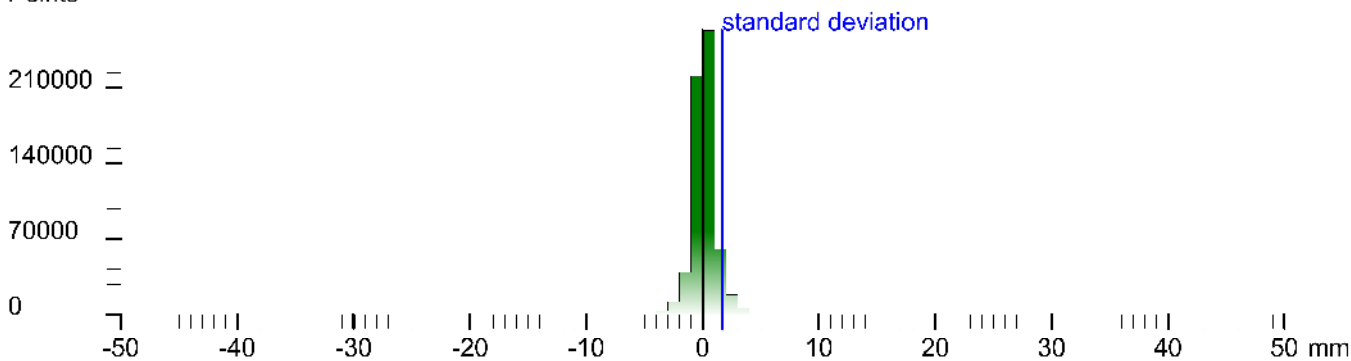
Registration matrix:

```
-0.316560  0.948572  0.000612  26.9695 m  
-0.948573 -0.316561 -0.000153 -1.6722 m  
0.000049 -0.000627  1.000000  1.0766 m  
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation: 1.7 mm

Deviation histogram

Points



Scan '20'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Scan position: '20' - name: '148:20' - sensor: 'Z+F IMAGER 5016' - serial: '5016-0100' - firmware: '9.0.3.6562-0' - resolution: 'High' - quality: 'Normal' - registration: 'cloud to cloud' - standard deviation: '1.7 mm' - points: '210000'
```

Sensors: 3096 'barometer (transition rotation)'
Barometer: 0.992015 bar / 78.3 m
nav translation: -2.5170 m -1.1141 m 178.773 m accuracies: 0.5018 m 0.5018 m 0.0000 m
nav rotation: 0.0000 0.0000 0.0000 accuracies: 0.0000 0.0000 1s.0000
upside-down: no
Initial pre position: (Girdoor)
-0.29° 0.956 0.000 -7.651
-0.996 -0.284 0.000 -11.0°
0.000 0.000 1.000 -2.600
0.000 0.000 0.000 1.000

Level system info: dynamic compensator available.



Scan position '21'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

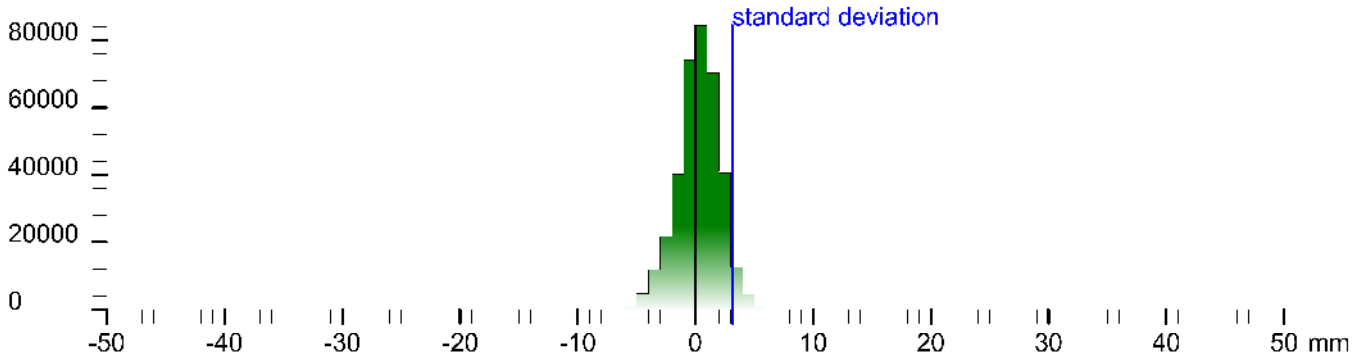
Registration matrix:

```
-0.148235  0.988952  0.000753  30.3334 m  
-0.988953 -0.148236 -0.000061 -0.9654 m  
0.000053 -0.000753  1.000000  -0.2406 m  
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation:3.1 mm

Deviation histogram

Points



Scan '21'

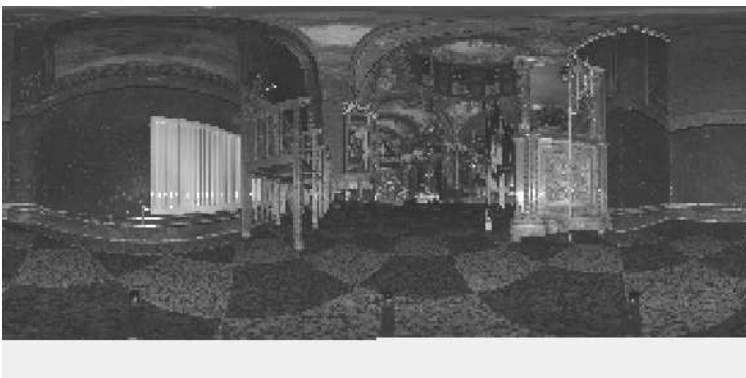
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: '148235 0.988952 0.000753 30.3334 m  
-0.988953 -0.148236 -0.000061 -0.9654 m  
0.000053 -0.000753 1.000000 -0.2406 m  
0.000000 0.000000 0.000000 1.0000'  
Sensor  
sensors: 3096 'barometric transition rotation'  
Barometer: 0.992233 bar '76.45' m  
nav translation: -3.7773 m -1.3783 m 176.6857 m accuracies: 7.1140 m 7.1140 m 0.0000 m  
nav rotation: 0.0000 0.0000 0.0000 accuracies: 0.0000 0.0000 1s.0000  
upside-down: no  
Initial pre position: (Girdoor)  
-3.243 0.970 0.000 -11.13'  
-0.970 -0.245 0.000 -12.089  
0.000 0.000 1.000 -4.091  
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '23'

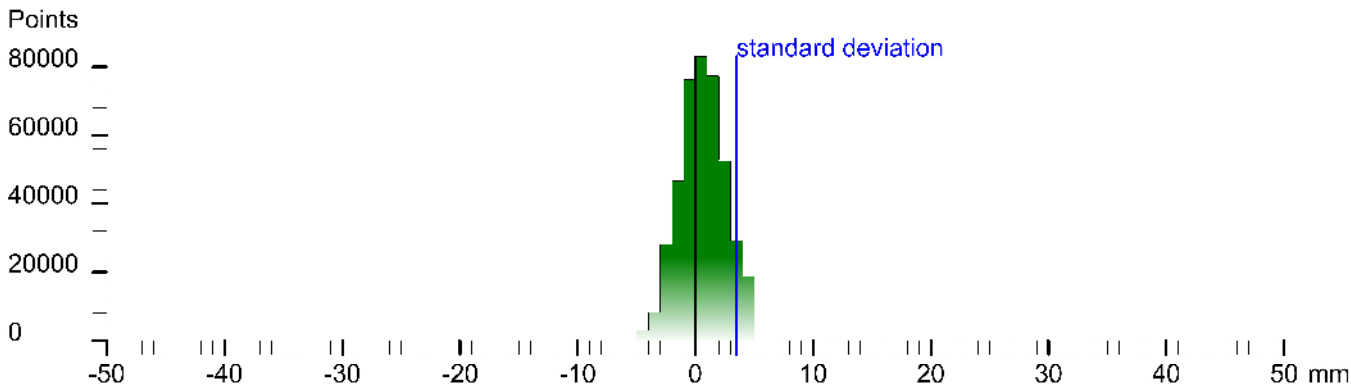
Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```

0.277001  0.960870  0.000555  31.1167 m
-0.960870  0.277000  0.000226  3.8132 m
0.000065  -0.000594  1.000000  -0.4098 m
0.000000  0.000000  0.000000  1.0000
  
```

Result registration cloud to cloud standard deviation: 3.5 mm

Deviation histogram



Scan '23'

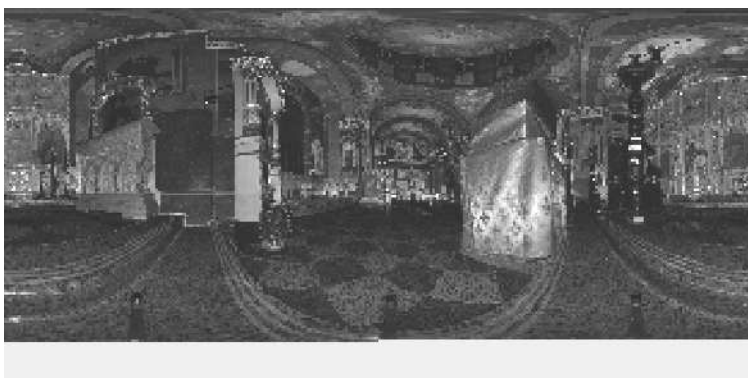
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```

Scan: 2015-11-10 11:14:23
Sensor:
sensors: 3096 'barometric rotation'
Barometer: 0.992292 bar / 75.953 m
nav translation: 8.9984 m 4.0518 m 175.0109 m accuracies: 10.0548 m 10.0548 m 0.0000 m
nav rotation: 0.0000 0.0000 / 9.1937 / accuracies: 0.0000 0.0000 / 0.0000
up/down: no
Initial position: (Girdoor)
0.787 0.982 0.000 -4.422
-0.982 0.187 0.000 -8.074
0.000 0.000 1.000 -5.166
0.000 0.000 0.000 1.000
  
```

Level system info: dynamic compensator available.



Scan position '24'

Scan position is member of group(s):

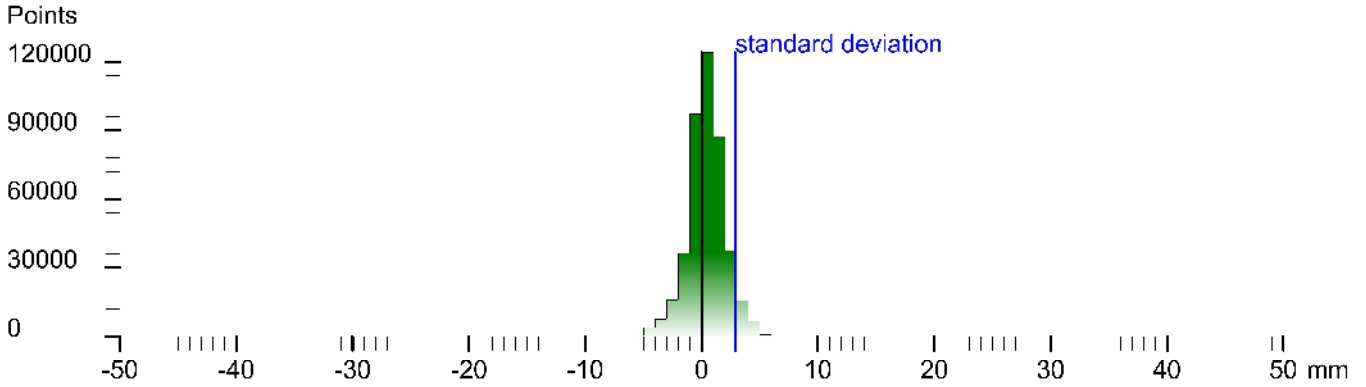
Status registration '[102h] registered with cloud to cloud'

Registration matrix:

```
-0.196016  0.980601  0.000441  34.1288 m  
-0.980600 -0.196016 -0.000015  2.9977 m  
0.000072 -0.000433  1.000000  1.1529 m  
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation: 2.9 mm

Deviation histogram



Scan '24'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
----------	-------

comment	
operator	
Sensors: 3096 'barometric transition rotation'	
Barometer: 0.992170 bar / 76.985 m	
nav translation: 3.6530 m -2.1817 m 176.7669 m accuracies: 7.22/0 m 7.22/40 m 0.0000 m	
nav rotation: 0.0000 0.0000 /s.8882 accuracies: 0.0000 0.0000 /s.0000	
upside-down: no	
Initial pre position: (Girdoor)	
0.245 0.970 0.000 -0.789	
-0.9/0 0.245 0.000 -10.20E	
0.000 0.000 1.000 -4.010	
0.000 0.000 0.000 1.000	

Level system info: dynamic compensator available.



Scan position '25'

Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

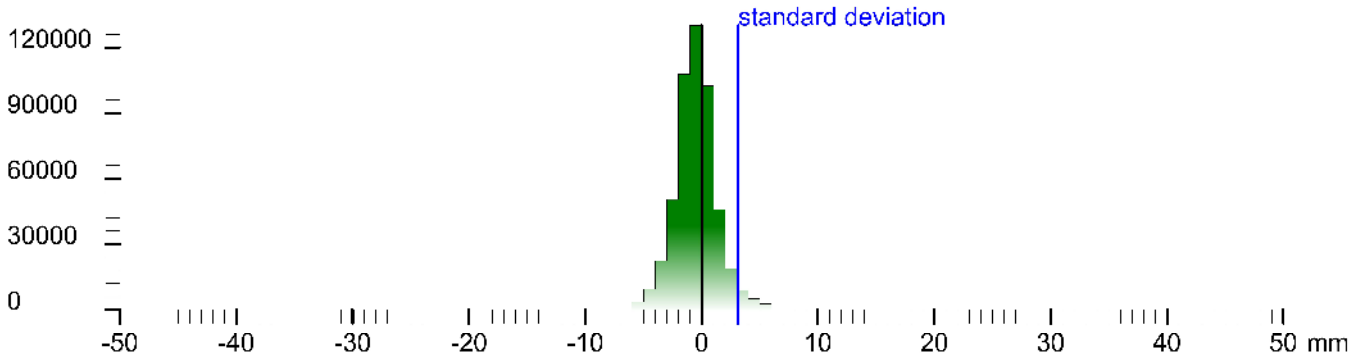
```

0.949611  0.313437  0.000310  31.9873 m
-0.313437 0.949610  0.000310  6.9231 m
-0.000195 -0.000392 1.000000  1.0548 m
0.000000  0.000000  0.000000  1.0000
    
```

Result registration cloud to cloud standard deviation:3.1 mm

Deviation histogram

Points



Scan '25'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```

Scan comment: cat [102h] [03] + name: 1-01-25 + name: 25 + pos: '25' of '1-01-25' + pos: '25' of '1-01-25' + pos: '25' of '1-01-25'
Sensor
sensors: 3096 "barometric transition rotation"
Barometer: 0.992591 bar 73.425 m
nav translation: 0.0000 m 0.0000 m 172.8769 m accuracies: 5.1000 m 5.1000 m 3.0000 m
nav rotation: 0.0000 0.0000 1.0987 accuracies: 0.0000 0.0000 15.0000
up/down: no
Initial pre position (Girdner)
0.856 0.294 0.000 -0.789
-0.294 0.916 0.000 -10.20E
0.000 0.000 1.000 -7.500
0.000 0.000 0.000 1.000
    
```

Level system info: dynamic compensator available.



Scan position '26'

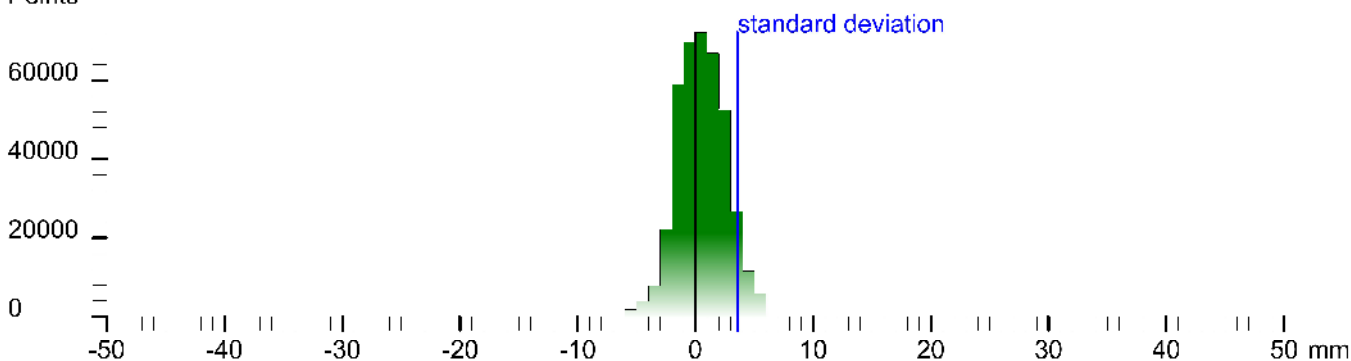
Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```
0.562800  0.826594  0.000390  32.7326 m
-0.826593  0.562800  0.000192  11.7245 m
-0.000059 -0.000429  1.000000  1.1530 m
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation:3.6 mm

Deviation histogram

Points



Scan '26'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Scan comment: '148:26' sensor: 'Z+F IMAGER 5016' serial: '5016-0100' firmware: '9.0.3.6562-0' resolution: 'High' quality: 'Normal'
Sensor
sensors: 3096 *barometer transition rotation*
Barometer: 0.992598 bar ~73.368 m
nav translation: 1.0338 m 1.0905 m 172.8623 m accuracies: 7.2084 m 7.2084 m 0.0000 m
nav rotation: 0.0000 0.0000 47.6327 accuracies: 0.0000 0.0000 15.0000
upside-down: no
Initial pos position: (0,0,0)
0.671 0.738 0.000 3.244
-0.738 0.674 0.000 -9.116
0.000 0.000 1.000 -7.915
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '27'

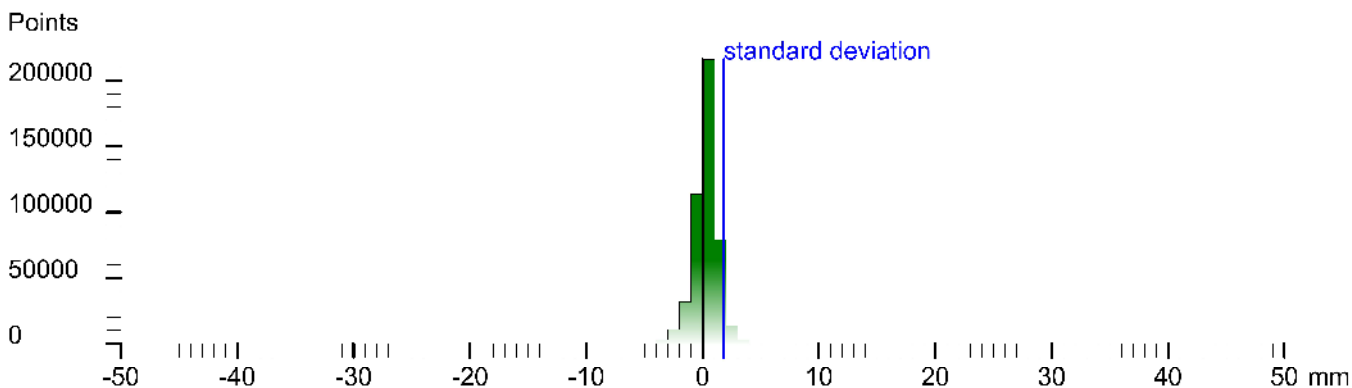
Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```

0.945150  0.326640  0.000465  34.8945 m
-0.326640  0.945149  0.000226  7.5979 m
-0.000365 -0.000366  1.000000  1.1471 m
0.000000  0.000000  0.000000  1.0000
    
```

Result registration cloud to cloud standard deviation: 1.8 mm

Deviation histogram



Scan '27'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```

Scan position: '148:102h' - name: '148:27' - sensor: 'Z+F IMAGER 5016' - serial: '5016-0100' - firmware: '9.0.3.6562-0' - scan resolution: 'High' - quality: 'Normal' - registration: 'cloud to cloud' - standard deviation: '1.8 mm' - points: '207461794'
Sensor
sensors: 3096 *barometer transition rotation*
Barometer: 0.992524 bar ~ 73.993 m
nav translation: -1.7076 m -2.2950 m 173.3876 m accuracies: 0.5761 m 0.5761 m 0.0000 m
nav rotation: 0.0000 0.0000 *3.2099 accuracies: 0.0000 0.0000 15.0000
upside-down: no
Initial prc position: (Girdoor)
0.971 0.228 0.000 1.477
-0.228 0.974 0.000 -11.411
0.000 0.000 1.000 -7.389
0.000 0.000 0.000 1.000
    
```

Level system info: dynamic compensator available.



Scan position '28'

Scan position is member of group(s):

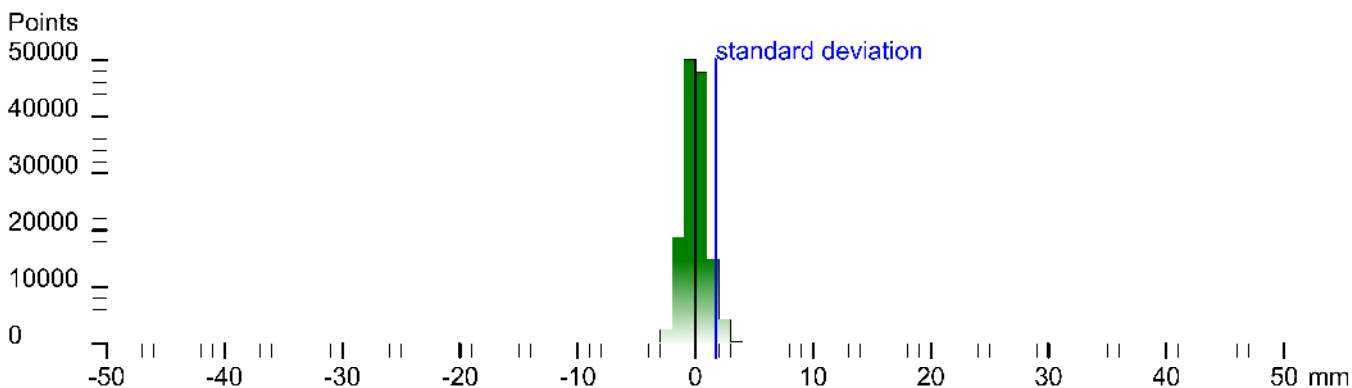
Status registration '[102h] registered with cloud to cloud'

Registration matrix:

```
0.377203 -0.926131 0.000514 35.9830 m
0.926130 0.377203 0.000306 13.8352 m
-0.000478 0.000358 1.000000 1.1496 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 1.7 mm

Deviation histogram



Scan '28'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Scan comment: null
Sensor
sensors: 3096 *barometric transition rotation*
Barometer: 0.992699 bar / 73.356 m
nav translation: 1.5727 m -3.0104 m 173.1493 m accuracies: 0.5252 m 0.9252 m 0.0001 m
nav rotation: 0.0000 0.0000 2/8.3341 accuracies: 0.0000 0.0000 15.0000
upside-down: no
Initial pre position: (Girdoor)
0.145 -0.989 0.000 3.049
0.989 0.145 0.000 -4.461
0.000 0.000 1.000 -7.628
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '29'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

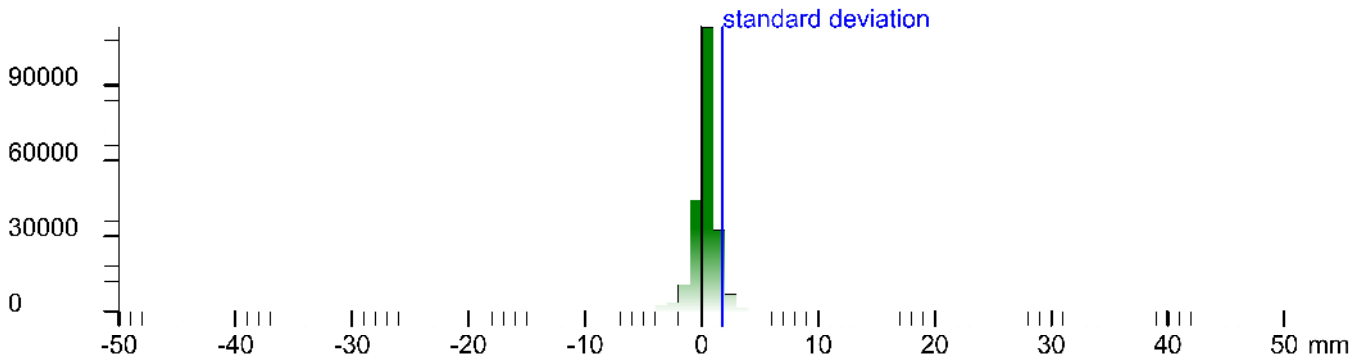
Registration matrix:

```
0.887956 0.459930 0.000638 38.8422 m
-0.459931 0.887955 0.000327 9.7678 m
-0.000414 -0.000585 1.000000 1.1472 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 1.8 mm

Deviation histogram

Points



Scan '29'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: full 1908x1031 mm scale 148:29 meters 2019-08-29 10:00:00  
Sensor  
sensors: 3096 *barometric transition rotation*  
Barometer: 0.992640 bar ~ 73.008 m  
nav translation: -3.3081 m -2.9510 m 172.5435 m accuracies: 0.0168 m 0.0168 m 0.0000 m  
nav rotation: 0.0000 0.0000 21.1142 accuracies: 0.0000 0.0000 15.0000  
upside-down: no  
Initial pre position: (Girdoor)  
0.929 0.370 0.000 2.741  
-0.370 0.929 0.000 -1.402  
0.000 0.000 1.000 -5.237  
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '3'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

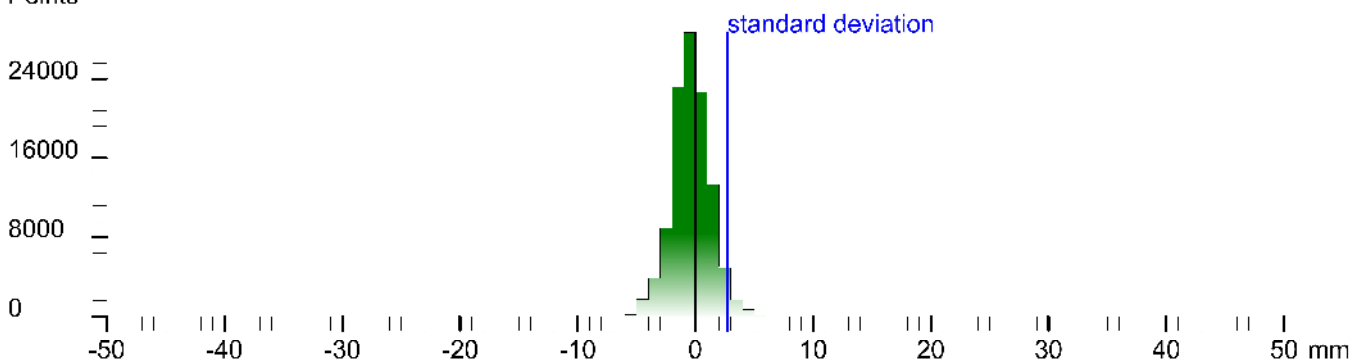
Registration matrix:

```
-0.620188 -0.784454 0.000394 5.7440 m
0.784454 -0.620188 -0.000278 4.5929 m
0.000462 0.000138 1.000000 0.7576 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:2.7 mm

Deviation histogram

Points



Scan '3'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata Value comment operator

```
Scan comment: 'Z+F IMAGER 5016' serial number '5016-0100' Firmware '9.0.3.6562-0'
Sensor
sensors: '3096' (barometric transition rotation)
Barometer: 0.991635 bar / 81.52 m
nav translation: 0.6794 m 3.6593 m 180.9301 m accuracies: 7.0636 m 7.0636 m 3.0000 m
nav rotation: 0.0000 0.0000 228.8353 accuracies: 0.0000 0.0000 1s.0000
upside-down: no
Initial pre position: (0:indoor)
-3.658 -0.753 0.000 0.675
0.753 -0.658 0.000 3.659
0.000 0.000 1.000 0.153
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



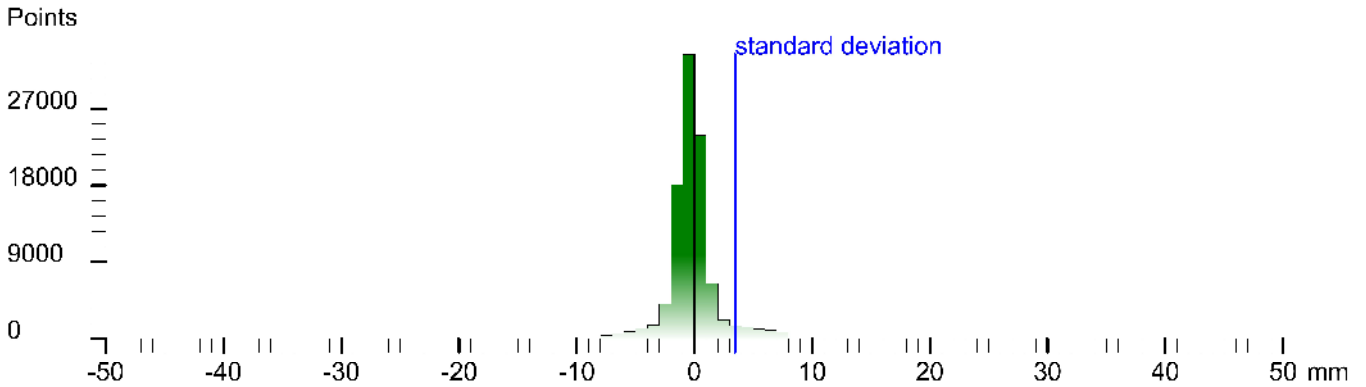
Scan position '31'

Scan position is member of group(s):
Status registration '[102h] registered with cloud to cloud'
Registration matrix:

```
0.843272 -0.537489 0.001027 38.3623 m  
0.537489 0.843271 0.000259 2.5033 m  
-0.001005 0.000332 1.000000 1.1483 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 3.4 mm

Deviation histogram



Scan '31'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

Sensor

sensors: 3096 *barometric transition rotation*
Barometer: 0.992792 bar * 71.724 m
nav translation: -3.0716 m -2.3830 m 17.3352 m accuracies: 6.9661 m 6.9661 m 0.0000 m
nav rotation: 0.0000 0.0000 296.9072 accuracies: 0.0000 0.0000 1s.0000
upside-down: no
Initial pos position: (0/door)
0.152 -0.892 0.000 -2.722
0.692 0.462 0.000 -20.662
0.000 0.000 1.000 -9.442
0.000 0.000 0.000 1.000

Level system info: dynamic compensator available.



Scan position '32'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

Registration matrix:

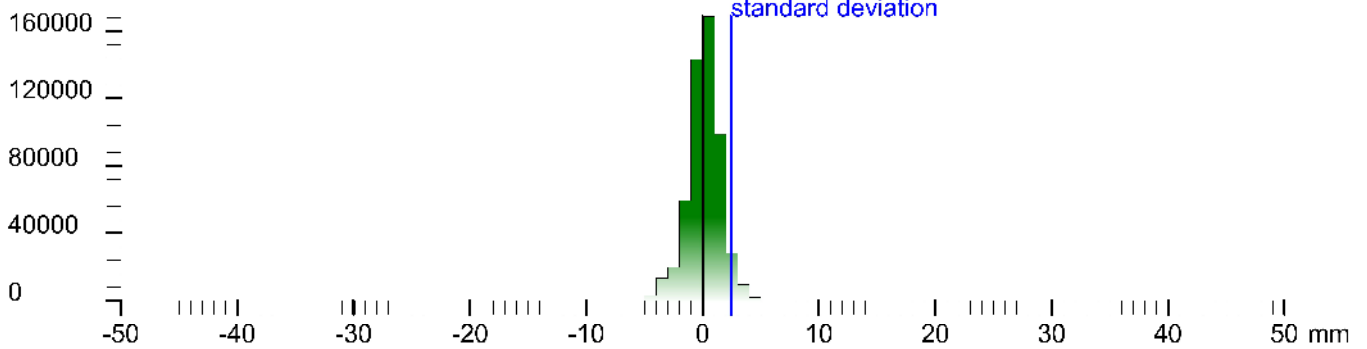
```

0.747315 -0.664471 0.000382 29.9471 m
0.664472 0.747315 0.000314 9.8453 m
-0.000494 0.000017 1.000000 -0.4205 m
0.000000 0.000000 0.000000 1.0000
    
```

Result registration cloud to cloud standard deviation: 2.4 mm

Deviation histogram

Points



Scan '32'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

Sensor: 3096 *barometric transition rotation*

Barometer: 0.993057 bar ~ 89.48 m
 nav translation: 8.7708 m 0.3204 m 108.2793 m accuracies: 9.2770 m 9.2770 m 0.0000 m
 nav rotation: 0.0000 0.0000 0.0000 accuracies: 0.0000 0.0000 1s.0000
 up/down: no

Initial pre position: (Girdoor)
 0.768 -0.670 0.000 6.018
 0.640 0.768 0.000 -20.382
 0.000 0.000 1.000 -1.488
 0.000 0.000 0.000 1.000

Level system info: dynamic compensator available.



Scan position '34'

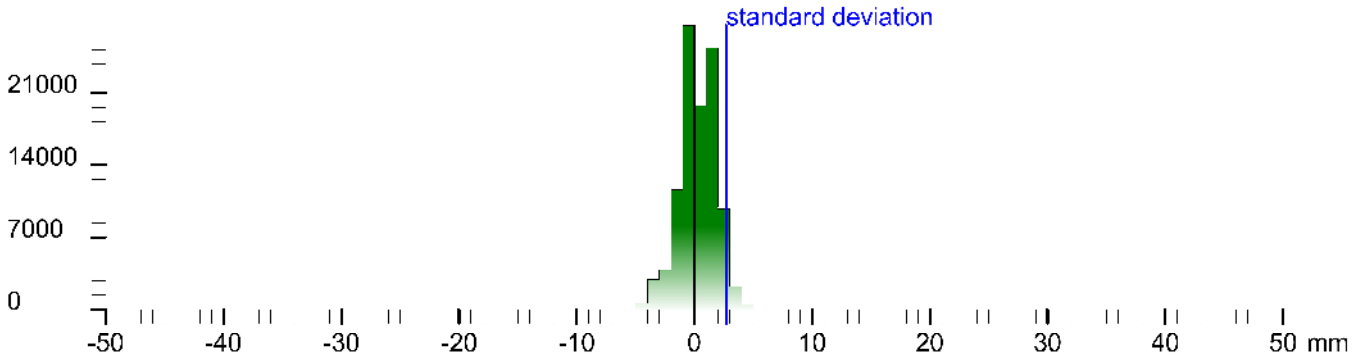
Scan position is member of group(s):
Status registration '[102h] registered with cloud to cloud'
Registration matrix:

```
-0.426565  0.904456  0.001149  30.9915 m  
-0.904458 -0.426565 -0.000519  2.1396 m  
0.000021 -0.001259  0.999999 -0.6116 m  
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation:2.7 mm

Deviation histogram

Points



Scan '34'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: '1.19.2016 10:31' filename: '1.46.154' scanid: '34' path: 'B:\1\6\1' camera: 'B:\1\6\1' sensor: 'Z+F IMAGER 5016' resolution: 'High' quality: 'Normal' registration: 'cloud to cloud' standard deviation: '2.7' result: 'OK' for: '1.20.16.1' for: '1.20.16.1' 34'
```

Sensor
sensors: 3096 *barometric transition rotation*
Barometer: 0.993107 bar ~ 89.057 m
nav translation: -3.7080 m -13.2272 m 168.7556 m accuracies: 12.0813 m * 2.0813 m 0.0000 m
nav rotation: 0.0000 0.0000 * 37.4870 accuracies: 0.0000 0.0000 16.0000
upside-down: no
Initial pre position: (Girdner)
-3.737 0.676 0.000 4.663
-0.676 -0.737 0.000 -52.533
0.000 0.000 1.000 -7.021
0.000 0.000 0.000 1.000

Level system info: dynamic compensator available.



Scan position '35'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

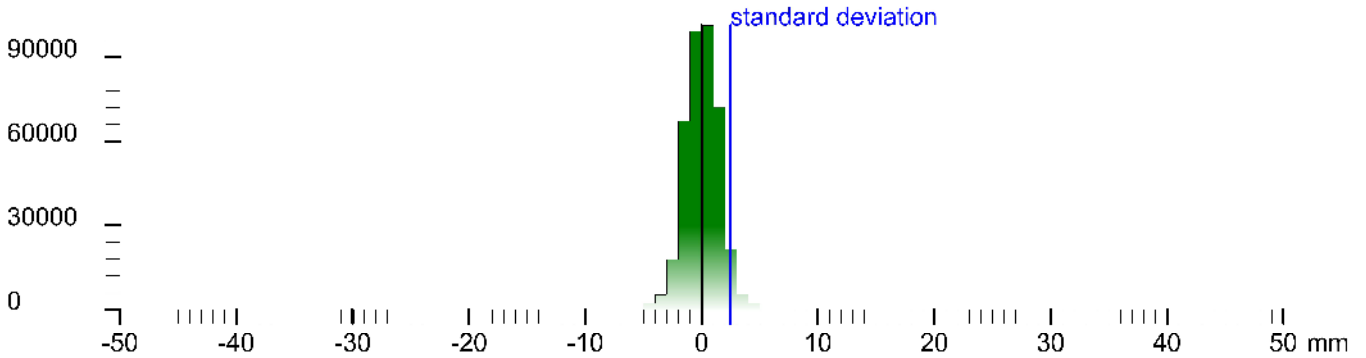
Registration matrix:

```
0.664284 -0.747482 -0.000331 10.3389 m
0.747482 0.664284 0.000314 4.9725 m
-0.000016 -0.000457 1.000000 1.9572 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 2.5 mm

Deviation histogram

Points



Scan '35'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Scan comment: null
Sensor
sensors: 3096 "barometric transition rotation"
Barometer: 0.997402 bar "32.78" m
nav translation: 0.0000 m 0.0000 m 132.0741 m accuracies: 5.1000 m 5.1000 m 3.0000 m
nav rotation: 0.0000 0.0000 509.7963 accuracies: 0.0000 0.0000 1s.0000
upside-down: no
Initial pre position: (Girdoor)
0.640 -0.768 0.000 4.663
0.768 0.640 0.000 -32.533
0.000 0.000 1.000 -48.703
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '37'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

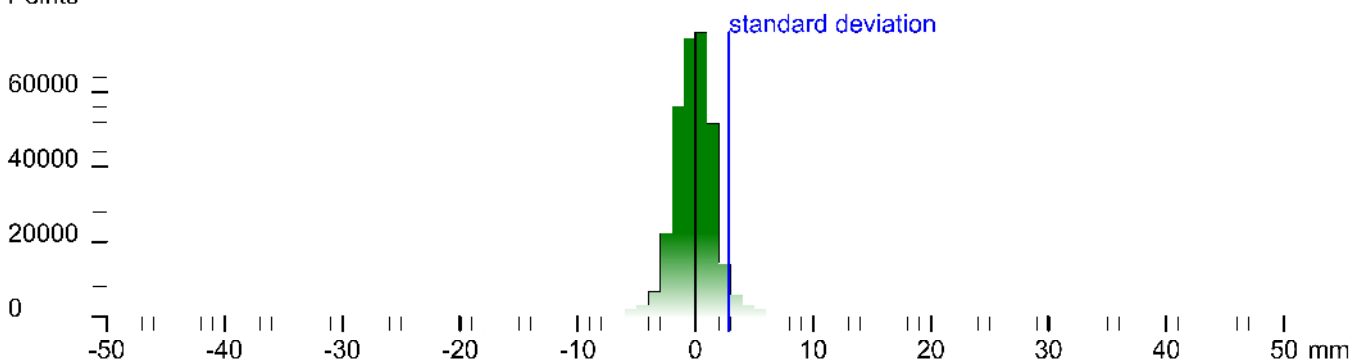
Registration matrix:

```
0.700044 -0.714099 -0.000033 14.5254 m  
0.714101 0.700044 0.000065 -0.6226 m  
-0.000022 -0.000070 1.000000 7.3687 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:2.9 mm

Deviation histogram

Points



Scan '37'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata Value
comment
operator

```
Scan position: '37' member of group(s): '37' registration: '102h' registered with cloud to cloud  
Sensor  
sensors: 3096 *barometric transition rotation*  
Barometer: 0.996644 bar *39.167 m  
nav translation: -2.2078 m -2.1053 m 138.8095 m accuracies: 0.7/26 m 0.7/26 m 0.0000 m  
nav rotation: 0.0000 0.0000 503.9632 accuracies: 0.0000 0.0000 1s.0000  
upside-down: no  
Initial pre position: (Girdoor)  
0.559 -0.829 0.000 2.711e  
0.529 0.008 0.000 -41.867  
0.000 0.000 1.000 1.000  
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '38'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

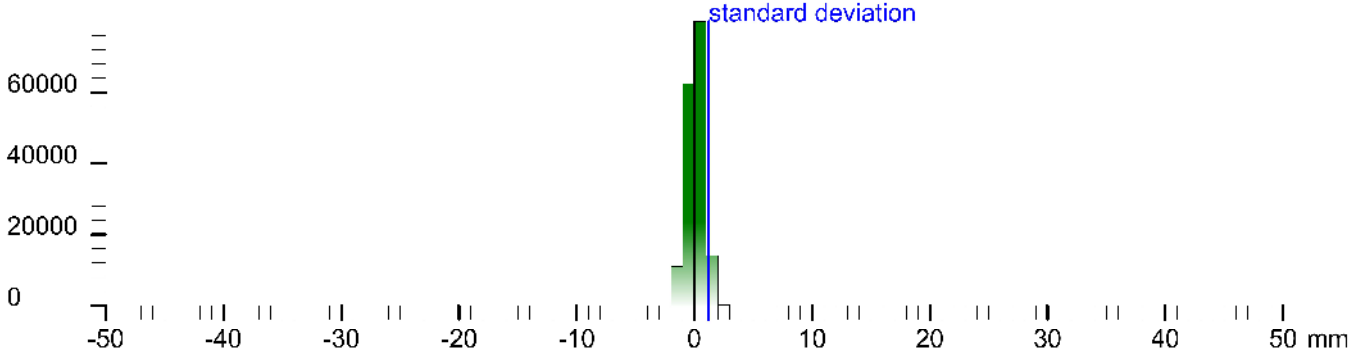
Registration matrix:

-0.367907	-0.929863	0.000032	11.2632 m
0.929863	-0.367909	0.000080	-2.9585 m
-0.000063	0.000057	1.000000	7.3818 m
0.000000	0.000000	0.000000	1.0000

Result registration cloud to cloud standard deviation:1.2 mm

Deviation histogram

Points



Scan '38'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata Value

comment	Value
operator	

Sensor: 3096 (barometric or transition rotation)

Barometer: 0.996810 bar / 39.462 m
nav translation: -2.8558 m 1.7810 m 138.5964 m accuracies: 0.508 m 0.508 m 0.0000 m
nav rotation: 0.0000 0.0000 0.0000 237.1373 accuracies: 0.0000 0.0000 15.0000
up/down: no
Initial pos position: (0/indoor)
-3.543 -0.840 0.000 4.640
0.640 0.543 0.000 -2.934
0.000 0.000 1.000 -42.181
0.000 0.000 0.000 1.000

Level system info: dynamic compensator available.



Scan position '39'

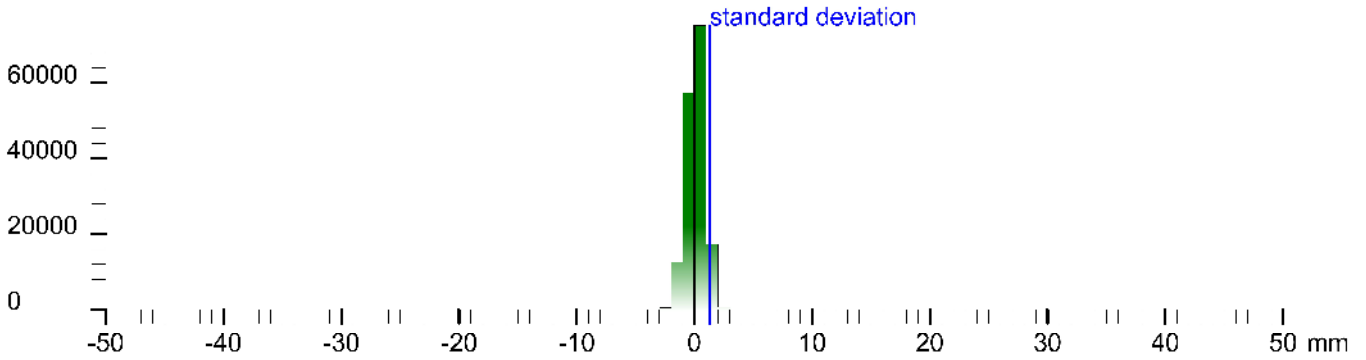
Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```
-0.163523 -0.986539 -0.000557 9.2812 m
0.986539 -0.163526 0.001687 4.0604 m
-0.001755 -0.000275 0.999999 7.3438 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 1.3 mm

Deviation histogram

Points



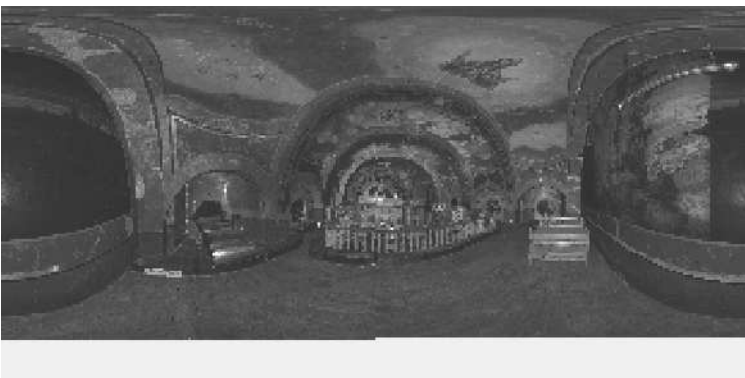
Scan '39'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

Sensor: 3096 *barometric transition rotation*
 Barometer: 0.996552 bar *39.943 m
 nav translation: -1.6180 m 1.4936 m 138.7734 m accuracies: 0.2114 m 0.2111 m 0.0000 m
 nav rotation: 0.0000 0.0000 250.9330 accuracies: 0.0000 0.0000 1s.0000
 up/down: no
 Initial pos position (0/door)
 -3.332 -0.943 0.000 3.021
 0.943 -0.332 0.000 -24.441
 0.000 0.000 1.000 -41.304
 0.000 0.000 0.000 1.000

Level system info: dynamic compensator available.



Scan position '4'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

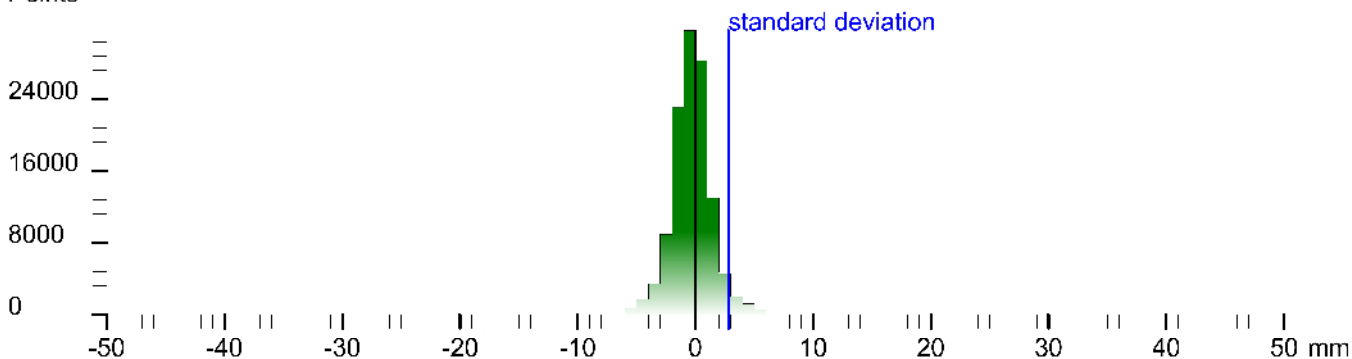
Registration matrix:

```
-0.721753  0.692152  0.000384  6.7424 m  
-0.692152 -0.721754  0.000278 -1.7595 m  
0.000471 -0.000064  1.000000  0.7443 m  
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation:2.8 mm

Deviation histogram

Points



Scan '4'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Scan comment: full 1.000000 3.000000 1.000000  
Sensor  
sensors: 3096 *barometric transition rotation*  
Barometer: 0.991887 bar / 81.079 m  
nav translation: -7.5065 m -3.9504 m 180.759 / m accuracies: 8.3338 m 9.3338 m 0.0000 m  
nav rotation: 0.0000 0.0000 0.428/33 accuracies: 0.0000 0.0000 1s.0000  
upside-down: no  
Initial pre position: (Girdoor)  
-3.797 0.604 0.000 -6.625  
-0.604 -0.787 0.000 0.009  
0.000 0.000 1.000 0.018  
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '41'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

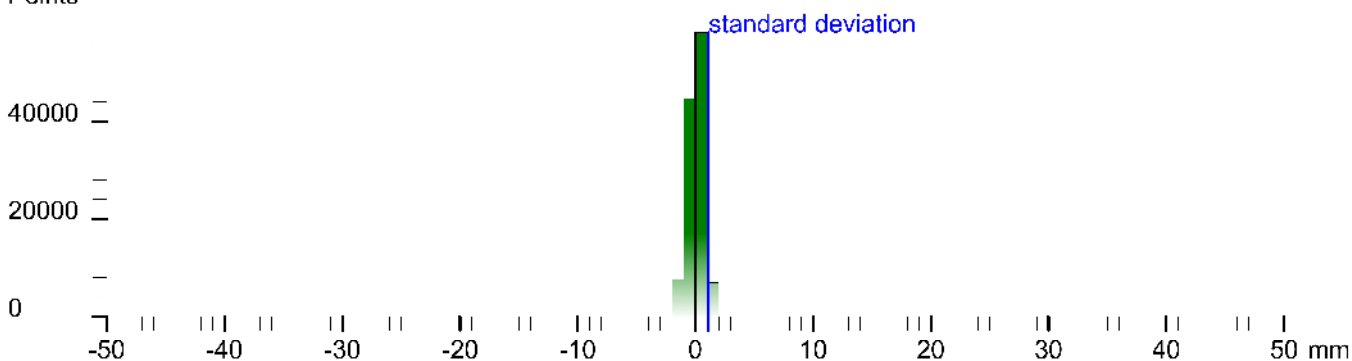
Registration matrix:

```
0.753743 0.657169 0.000156 9.3998 m
-0.657168 0.753745 0.001100 8.3228 m
0.000607 -0.000931 1.000000 6.6729 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 1.1 mm

Deviation histogram

Points



Scan '41'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Sensor: Z+F Imager 5016  
Sensors: 3096 *barometric transition rotation*  
Barometer: 0.996659 bar *39.042 m  
nav translation: -1.1987 m 1.3180 m 138.6728 m accuracies: 0.0177 m 0.0177 m 0.0000 m  
nav rotation: 0.0000 0.0000 61.5936 accuracies: 0.0000 0.0000 1s.0000  
upside-down: no  
Initial pre position (Girdoor)  
0.476 0.880 0.000 6.183  
-0.880 0.476 0.000 -12.688  
0.000 0.000 1.000 -42.204  
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '42'

Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

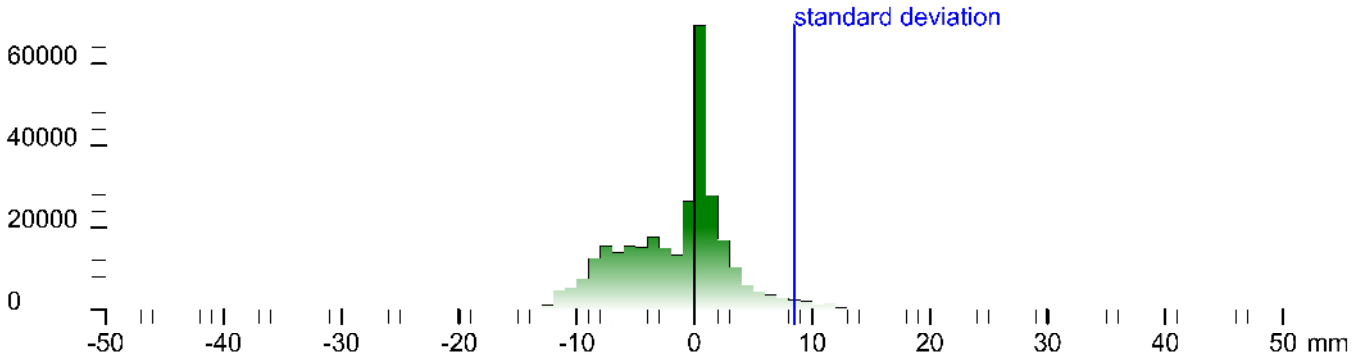
```

0.759045  0.651039  -0.000098  -3.8225 m
-0.651039  0.759045  0.000108  7.9509 m
0.000146  -0.000018  1.000000  0.3756 m
0.000000  0.000000  0.000000  1.0000
    
```

Result registration cloud to cloud standard deviation: 8.5 mm

Deviation histogram

Points



Scan '42'

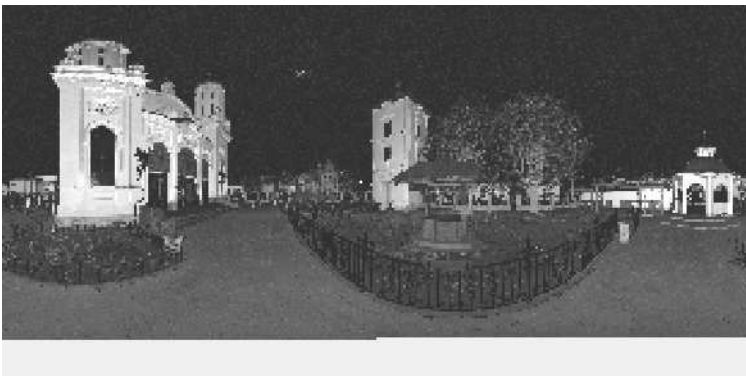
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```

Scan position: '42' - name: '42' - type: '42' - status: '42' - ...
Sensor
sensors: 3100 * barometer transition rotation gps
Barometer: 0.997233 bar -34.2 m
nav translation: -11.7960 m -7.508 m 32.9070 m accuracies: 2.2957 m 12.2957 m 0.0000 m
nav rotation: 0.0000 0.0000 0.0000 accuracies: 0.0000 0.0000 0.0000
upside-down: no
GPS lat: 44.943417 long: 26.029202 satellites: 3 height: 186.7m hdop: 4.4 vdcop: 1.0m hacc: 3.0m vacc: 12.0 tags: G2 'stand alone 2D solution'
Initial pre position (3-coor):
0.794 0.307 0.000 -5.616
-0.607 0.794 0.000 -20.196
0.000 0.000 1.000 -17.870
0.000 0.000 0.000 1.000
    
```

Level system info: dynamic compensator available.



Scan position '43'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

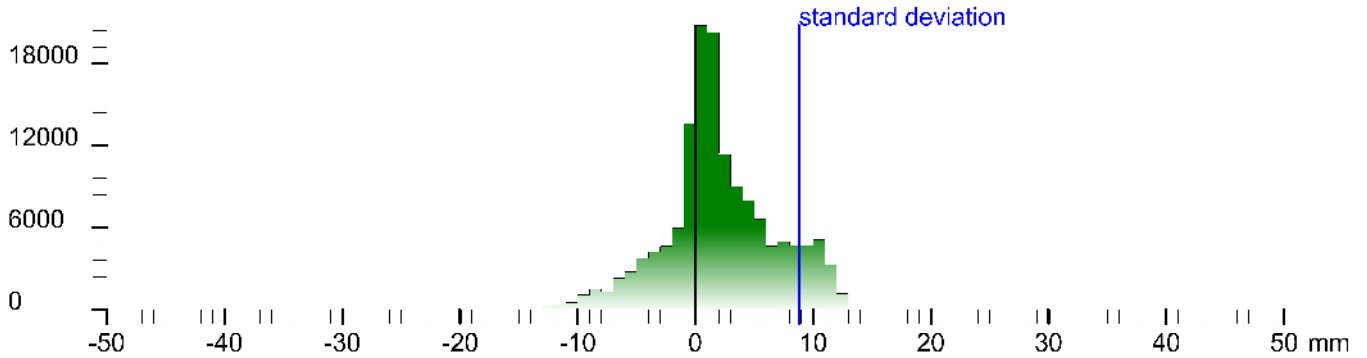
Registration matrix:

```
0.999937 -0.011312 -0.000093 -1.6838 m
0.011312 0.999937 0.000245 14.7648 m
0.000090 -0.000246 1.000000 0.5374 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:8.8 mm

Deviation histogram

Points



Scan '43'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Scan position: [102h] registered with cloud to cloud
Sensor
sensors: 3100 *barome or transition rotation gps
Barometer: 0.997171 bar -34.722 m
nav translation: 3.7618 m 3.5613 m 133.841° 8 m accuracies: 7.7021 m 7.7021 m 3.0000 m
nav rotation: 0.0000 0.0000 0.0000 366.83° 3 accuracies: 0.0000 0.0000 1s.0000
upside-down: no
GPS lat:44.943612 long:26 029228 satellites:5 height:102.0m hhdop:1.7 vhdop:2.5m hacc:5.7-m vacc:7.3 flags:G3 'stand alone 3D solution'
Initial pre position (3.o.tcoor):
0.998 -0.055 0.000 -4.616
0.055 0.998 0.000 - 3.108
0.000 0.000 1.000 -17.870
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '44'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

Registration matrix:

```

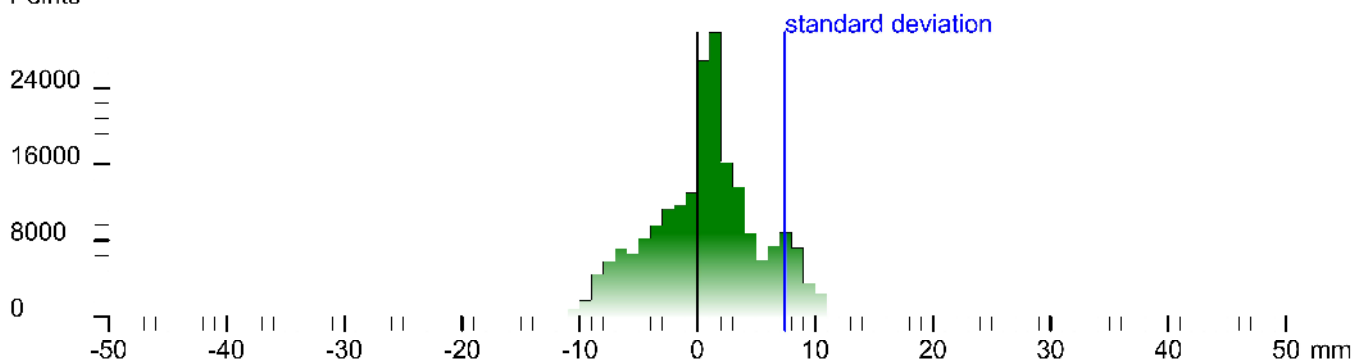
0.624391 -0.781113 -0.000380 7.3869 m
0.781113 0.624391 0.000128 15.2642 m
0.000137 -0.000377 1.000000 0.3469 m
0.000000 0.000000 0.000000 1.0000

```

Result registration cloud to cloud standard deviation: 7.5 mm

Deviation histogram

Points



Scan '44'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```

Scan comment: full 120sec 4000 samples 140000 samples 44' epoch 8176 m 7.3869 m 8176 m 7.3869 m 8176 m 7.3869 m 8176 m 7.3869 m 8176 m 7.3869 m 8176 m 7.3869 m 8176 m 7.3869 m 8176 m 7.3869 m 8176 m 7.3869 m
Sensor
sensors: 3100 * barometric transition rotation gps
Barometer: 0.997141 bar / 34.98" m
nav translation: 3.6128 m 5.4955 m 137.8191 m accuracies: 8.4220 m 8.4220 m 0.0000 m
nav rotation: 0.0000 0.0000 0.0000 310.7971 accuracies: 0.0000 0.0000 16.0000
upside-down: no
GPS lat: 44.943489 long: 26.029324 satellites: 6 height: 191.8m hhdop: 7.7 vdop: 2.3m hacc: 4.9-m vacc: 7.1 flags: G3 stand alone 3D solution
Initial pre position (3-coor):
0.653 -0.757 0.000 2.827
0.757 0.853 0.000 -21.842
0.000 0.000 1.000 -16.882
0.000 0.000 0.000 1.000

```

Level system info: dynamic compensator available.



Scan position '45'

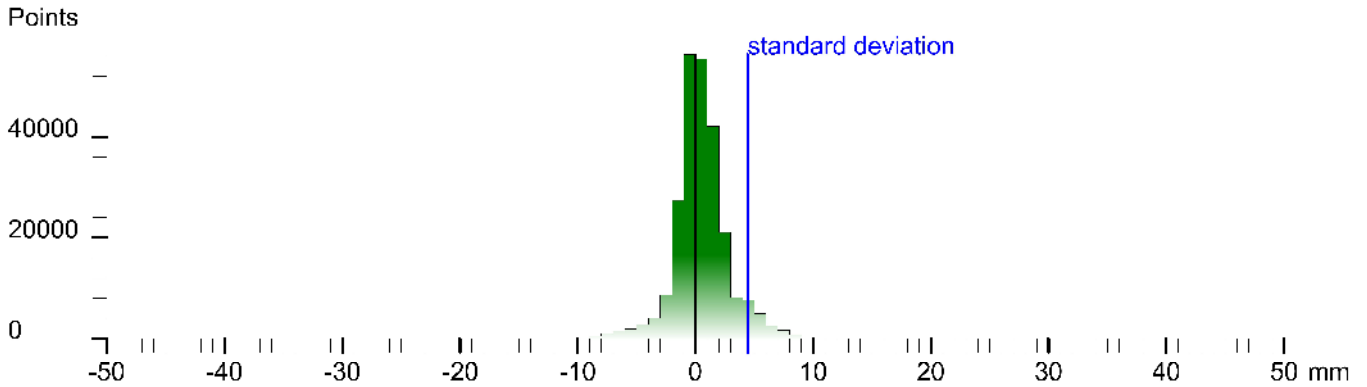
Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```

-0.202477  0.979288  0.000066  13.8897 m
-0.979288 -0.202477 -0.000022  11.7103 m
-0.000008 -0.000069  1.000000  0.3152 m
0.000000  0.000000  0.000000  1.0000
    
```

Result registration cloud to cloud standard deviation:4.4 mm

Deviation histogram



Scan '45'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```

Sensor
sensors: 3100 *barome or transition rotation gps
Barometer: 0.997070 bar *35.579 m
nav translation: 4.571 m 0.8537 m 134.9545 m accuracies: 7.4805 m 7.4805 m 0.0000 m
nav rotation: 0.0000 0.0000 *01.0163 accuracies: 0.0000 0.0000 1s.0000
upside-down: no
GPS lat:44.943775 long:26.029421 satellites:4 height:220.8m hdop:6.7 vdrop:5.8m hacc: 9.0m vacc:12.0 tags:G3 *stand alone 3D solution
Initial pre position (0:indoor)
-0.700 0.980 0.000 7.598
-0.980 -0.200 0.000 -20.986
0.000 0.000 1.000 -16.747
0.000 0.000 0.000 1.000
    
```

Level system info: dynamic compensator available.



Scan position '46'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

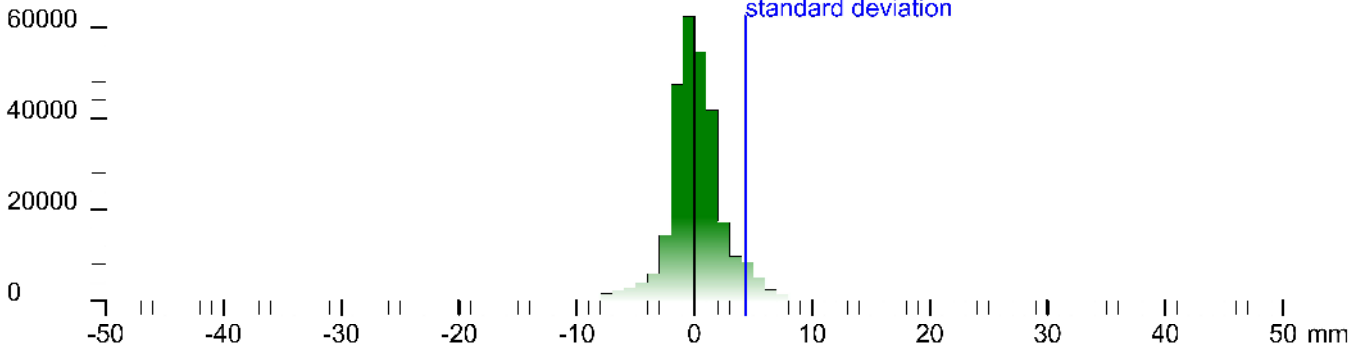
Registration matrix:

```
-0.988719 -0.149789 -0.000207 17.3808 m  
0.149789 -0.988719 -0.000213 16.2467 m  
-0.000173 -0.000241 1.000000 0.7163 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:4.3 mm

Deviation histogram

Points



Scan '46'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata Value comment operator

```
Scan comment: full 1.988719 0.149789 0.000207 17.3808 m  
Sensor  
sensors: 3100 *barome or transition rotation gps  
Barometer: 0.997151 bar / 34.89 m  
nav translation: 3.2434 m 1.4536 m 135.8190 m accuracies: 0.0289 m 0.0289 m 0.0000 m  
nav rotation: 0.0000 0.0000 -83.6279 accuracies: 0.0000 0.0000 1s.0000  
upside-down: no  
GPS lat:44.943894 long:26.029472 satellites:4 height:101.4m hddo:2.4 vdcop:3.6m hacc:9.4-m vacc:13.0 flags:G3's are also 3D solution'  
north:1977132.592 m east:423432.428 m zone:35T  
Initial pre position (3-coo. tocoor):  
-0.988 -0.06 0.000 10.841  
0.081 -0.998 0.000 -10.534  
0.000 0.000 1.000 -15.892  
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



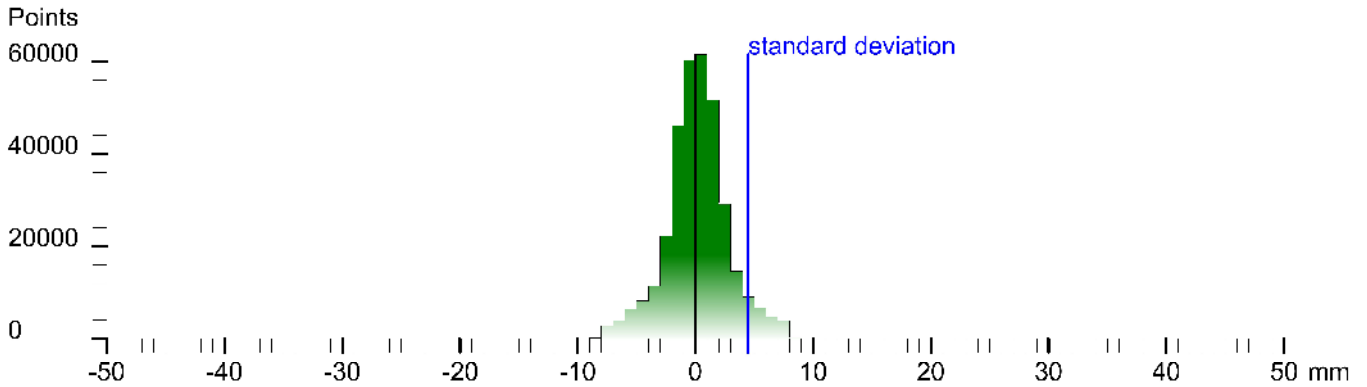
Scan position '47'

Scan position is member of group(s):
Status registration '[102h] registered with cloud to cloud'
Registration matrix:

```
0.649231 0.760593 -0.000575 20.4861 m
-0.760593 0.649231 0.000595 16.8698 m
0.000826 0.000051 1.000000 0.1292 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:4.5 mm

Deviation histogram



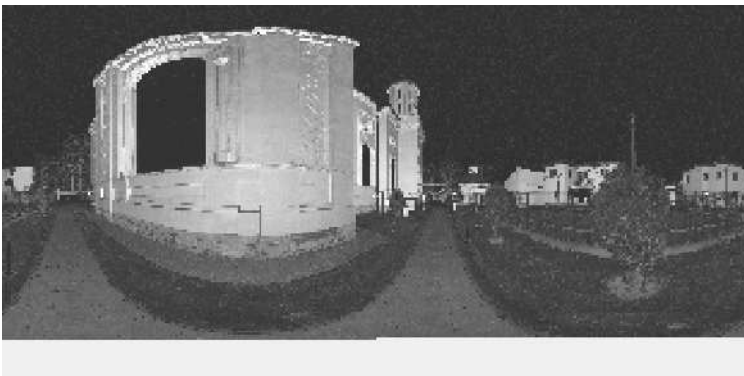
Scan '47'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

Sensor: 3100 * barometric transition rotation gps
Barometer: 0.997510 bar * 31.865 m
nav translation: 3.4080 m -0.4979 m 132.1843 m accuracies: 8.50/8 m 8.9048 m 0.0000 m
nav rotation: 0.0000 0.0000 48.0305 accuracies: 0.0000 0.0000 1s.0000
upside-down: no
GPS lat:44.943485 long:26.029409 satellites:4 height:188.9m hdop:3.0 vtdop:5.3m hacc:9.8-m vacc:15.0 flags:G3 's same sbrn 3D solution'
north:1977130 / 48 m east:423434.510 m zone:35T
Initial pre position (300, tocor):
0.689 0.744 0.000 14.248
-0.74 - 0.689 0.000 -26.032
0.000 0.000 1.000 -19.517
0.000 0.000 0.000 1.000

Level system info: dynamic compensator available.



Scan position '48'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

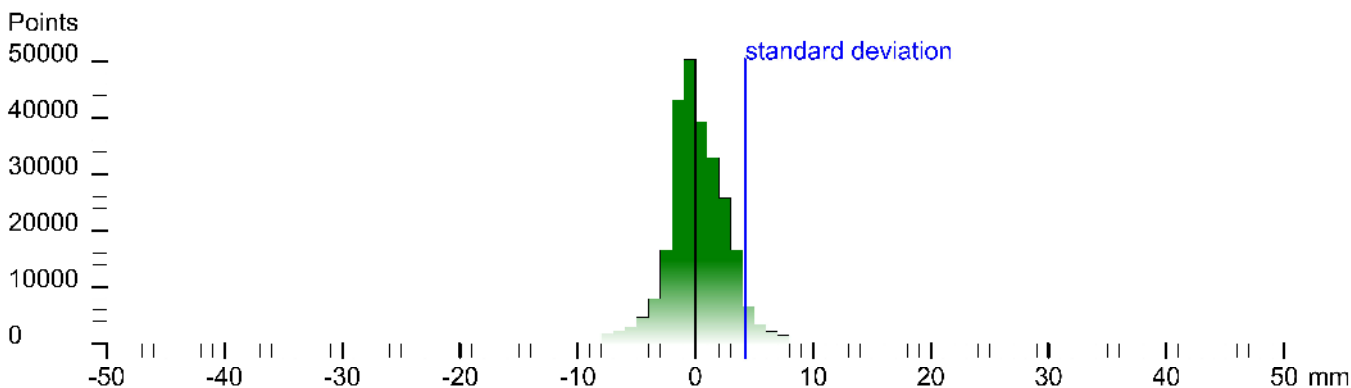
Registration matrix:

```

0.481790  0.876287  -0.000230  28.1625 m
-0.876287  0.481790  0.000701  18.3860 m
0.000725  -0.000136  1.000000  0.1010 m
0.000000  0.000000  0.000000  1.0000
    
```

Result registration cloud to cloud standard deviation:4.2 mm

Deviation histogram



Scan '48'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

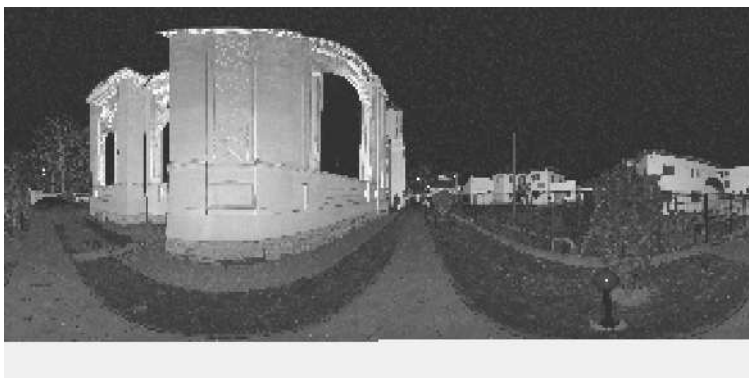
Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```

Scan position: lat:19.988403 lon:148.148748 alt:42.747878
Sensor
sensors: 3100 *barome or transition rotation gps
Barometer: 0.998039 bar *27.411 m
nav translation: 6.7592 m 0.5277 m 129.5647 m accuracies: 9.5577 m 9.5577 m 0.0000 m
nav rotation: 0.0000 0.0000 62.6079 accuracies: 0.0000 0.0000 1s.0000
upside-down: no
GPS sat:14.943497 long:26.029612 satellites:5 height:187.0m hddo:2.4 vdcp:3.7m hacc:1.0m vacc:15.0 fllgs:G3 *stand alone 3D solution*
north:1977131.613 m east:423443.407 m zone:35T
Initial pre position (3-coor):
0.480 0.888 0.000 *1.008
-0.888 0.480 0.000 *25.205
0.000 0.000 1.000 *52.147
0.000 0.000 0.000 1.000
    
```

Level system info: dynamic compensator available.



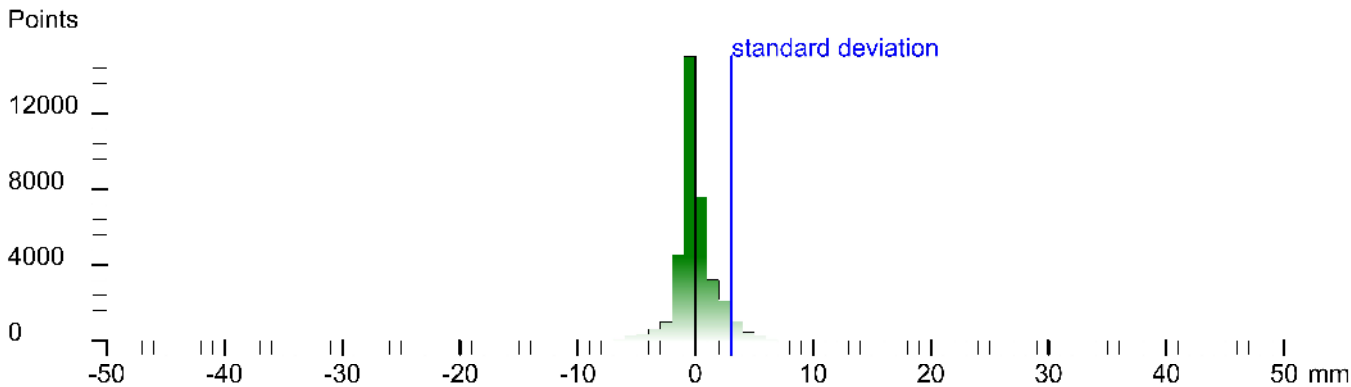
Scan position '5'

Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```
0.573080 -0.819500 -0.000024 8.7287 m
0.819500 0.573081 -0.000235 1.6862 m
0.000206 0.000114 1.000000 0.6666 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 3.1 mm

Deviation histogram



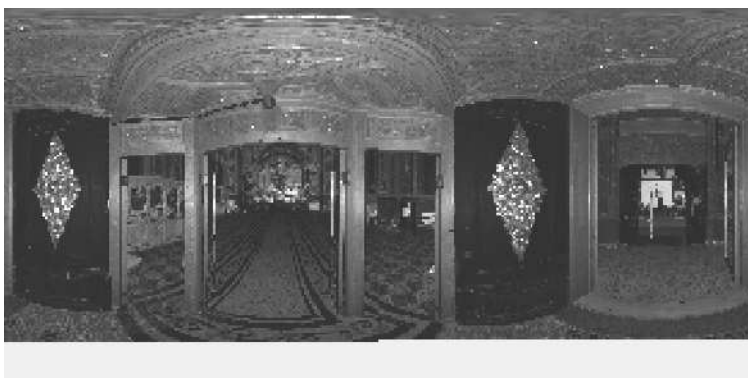
Scan '5'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Scan comment: null
Laser class: 305 mW max class: 146 mW
Sensors: 3096 *barometric transition rotation*
Barometer: 0.9918111 bar 180.025 m
nav translation: -2.4922 m 2.6832 m 180.0032 m accuracies: 0.9377 m 0.9377 m 0.0000 m
nav rotation: 0.0000 0.0000 0.0000 537.730 / accuracies: 0.0000 0.0000 1s,0.0000
upside-down: no
Initial pose position: (Girdoor)
0.612 -0.791 0.000 -9.317
0.791 0.612 0.000 2.692
0.000 0.000 1.000 -0.177
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '51'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

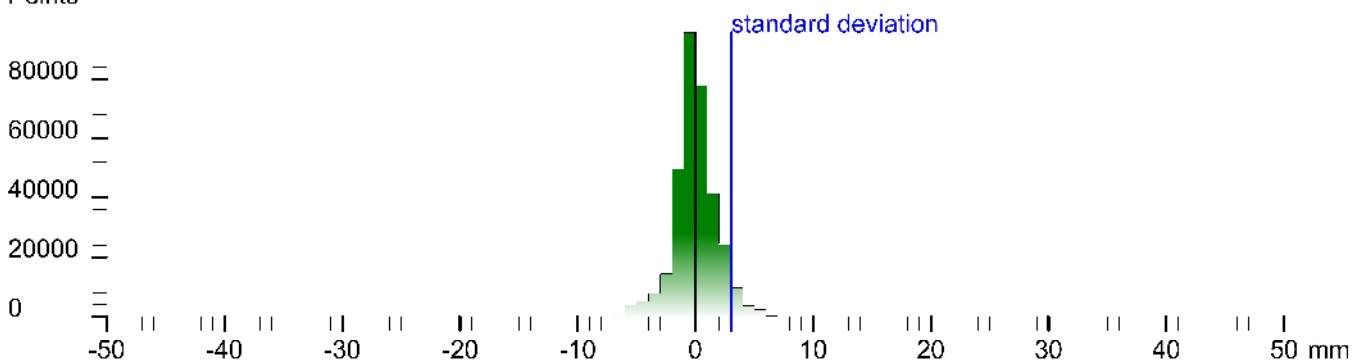
Registration matrix:

```
0.674184 0.738565 -0.000609 29.8420 m
-0.738565 0.674184 0.000377 18.6195 m
0.000689 0.000196 1.000000 0.1069 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:3.1 mm

Deviation histogram

Points



Scan '51'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: null  
Sensor  
sensors: 3096 *barometric transition rotation*  
Barometer: 0.997748 bar *29.863 m  
nav translation: 0.0000 m 0.0000 m 129.9475 m accuracies: 5.1000 m 5.1000 m 0.0001 m  
nav rotation: 0.0000 0.0000 47.5133 accuracies: 0.0000 0.0000 15.0000  
upside-down: no  
Initial pre position (Girdoor)  
0.678 0.735 0.000 21.038  
-0.735 0.678 0.000 -20.206  
0.000 0.000 1.000 -51.764  
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



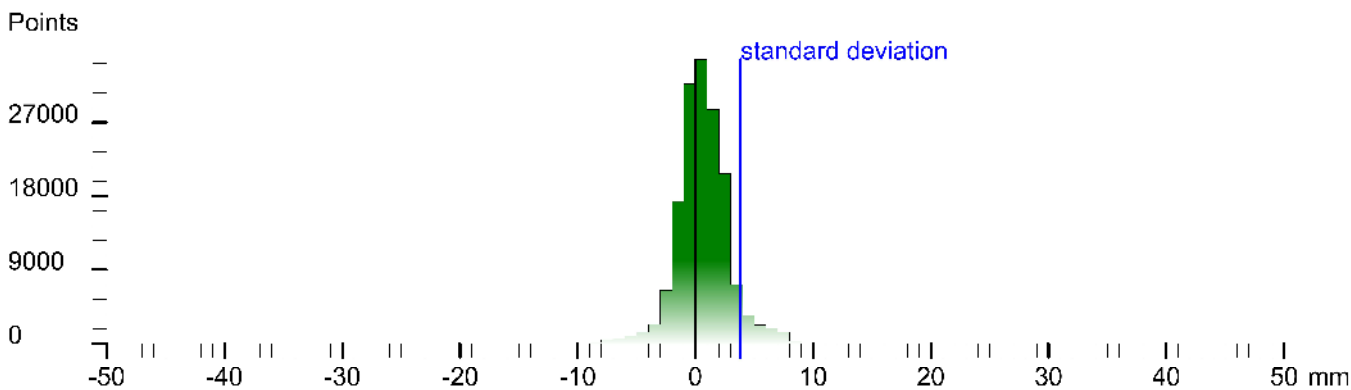
Scan position '53'

Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```
-0.440229  0.897886  0.000475  31.6798 m
-0.897888 -0.440229 -0.000172  14.0057 m
 0.000055 -0.000503  1.000000  0.1735 m
 0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation: 3.8 mm

Deviation histogram



Scan '53'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

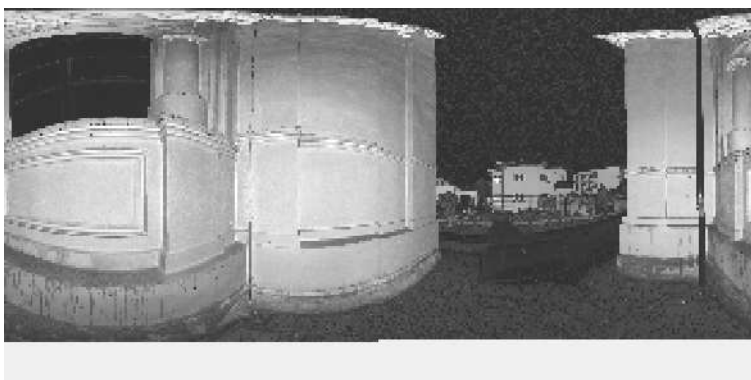
Metadata	Value
comment	
operator	

```
Scan coordinates: lat: 49.836403; lon: 10.15578; alt: 55.187; proj: UTM; zone: 32T; datum: WGS 84; ell: WGS 84; units: m; scale: 1.0; projection: Orthographic; sensor: Z+F Imager 5016; resolution: 0.25; quality: Normal; registration: cloud to cloud; standard deviation: 3.8; points: 2074641940
```

Sensors:
 sensors: 3096 'barometric transition rotation'
 Barometer: 0.997700 bar / 30.265 m
 nav translation: 0.5193 m -2.3159 m 128.1924 m accuracies: 0.318' m 0.318' m 0.0000 m
 nav rotation: 0.0000 0.0000 1.0000 accuracies: 0.0000 0.0000 15.0000
 up/down: no

Initial pre position (Girdoor):
 -3.361 0.933 0.000 21.828
 -0.983 -0.36' 0.000 -2/ 00'
 0.000 0.000 1.000 -52.518
 0.000 0.000 0.000 1.000

Level system info: dynamic compensator available.



Scan position '54'

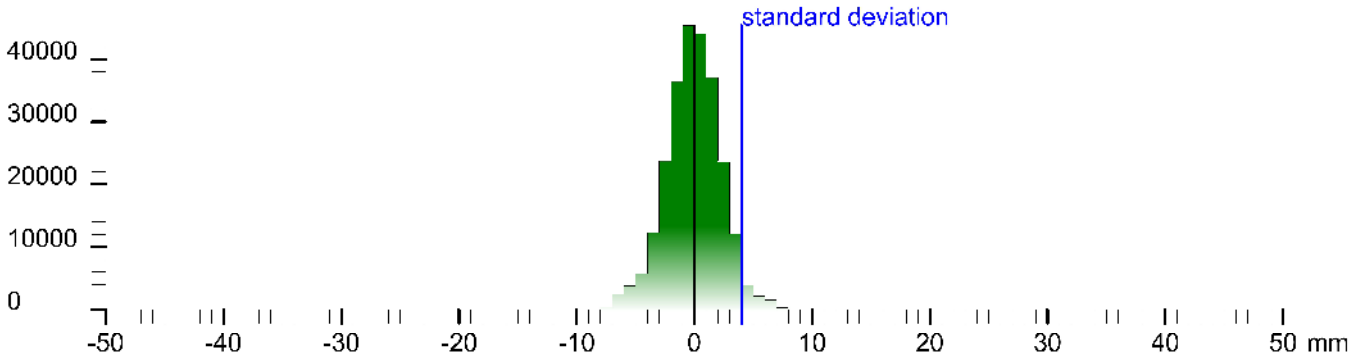
Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```
0.987049 -0.160418 -0.000842 35.1537 m
0.160419 0.987051 0.000498 19.7497 m
0.000751 -0.000626 1.000000 0.1022 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:4.0 mm

Deviation histogram

Points



Scan '54'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Scan position: [102h] registered with cloud to cloud
Sensor
sensors: 3100 *barometer/transition rotation/gps
Barometer: 0.997599 bar /31.17 m
nav translation: 1.7409 m 1.8413 m 130.3902 m accuracies: 6.3727 m 6.3727 m 3.0001 m
nav rotation: 0.0000 0.0000 347.8466 accuracies: 0.0000 0.0000 15.0000
upside-down: no
GPS lat:44.943627 long:26.029711 satellites:4 height:104.8m hdop:2.5 vdos:2.9m hacc:10.0m vacc:6.5 tags:G3 'stand alone 3D solution'
north:1977134.909 m east:423451.269 m zone:35T
Initial pre position (3-coo. tocoo):
0.978 -0.210 0.000 23.575
0.210 0.978 0.000 -25.708
0.000 0.000 1.000 -51.322
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '55'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

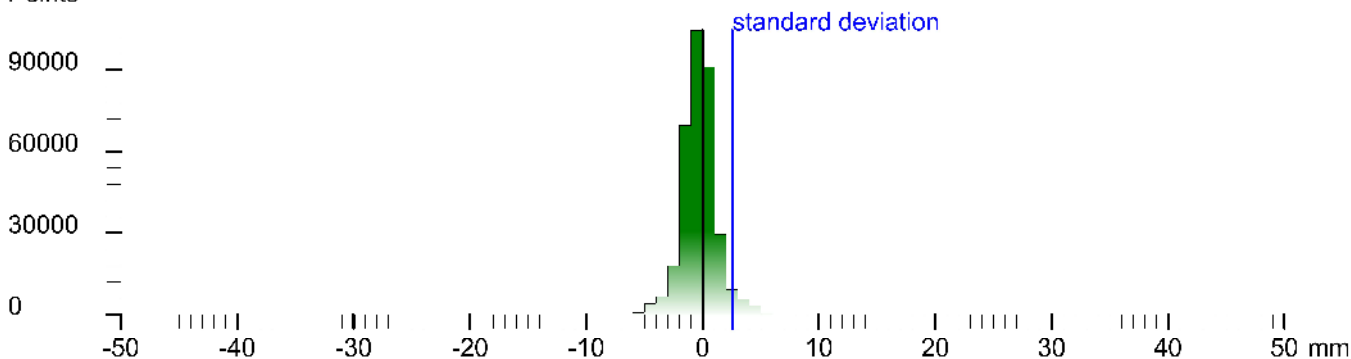
Registration matrix:

```
0.897050 0.441930 0.000541 37.8830 m
-0.441931 0.897051 0.000889 20.2350 m
-0.000093 -0.001036 1.000000 0.1070 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:2.6 mm

Deviation histogram

Points



Scan '55'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan position: lat:19.8484233 lon:14.1857440 alt:55.947167 m elevation:18.876 m position:0.000000 0.000000 0.000000  
Sensor  
sensors: 3100 *barometric transition rotation gps  
Barometer: 0.997480 bar *32.17 m  
nav translation: 2.300 m 0.8105 m 131.9271 m accuracies: 6.2104 m 6.2104 m 3.0000 m  
nav rotation: 0.0000 0.0000 24.12e3 accuracies: 0.0000 0.0000 1s.0000  
upside-down: no  
GPS:lat:14.943512 lon:26.029716 satellites:5 height:188.9m hhdop:1.5 vhdop:0.4m hacc:5.5m vacc:7.8 flags:G3 'stand alone 3D solution'  
north:1977133.209 m east:423451.700 m zone:35T  
Initial pre position (3.o. t.coor):  
0.913 0.409 0.000 33.883  
-0.409 0.913 0.000 -19.857  
0.000 0.000 1.000 -19.787  
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



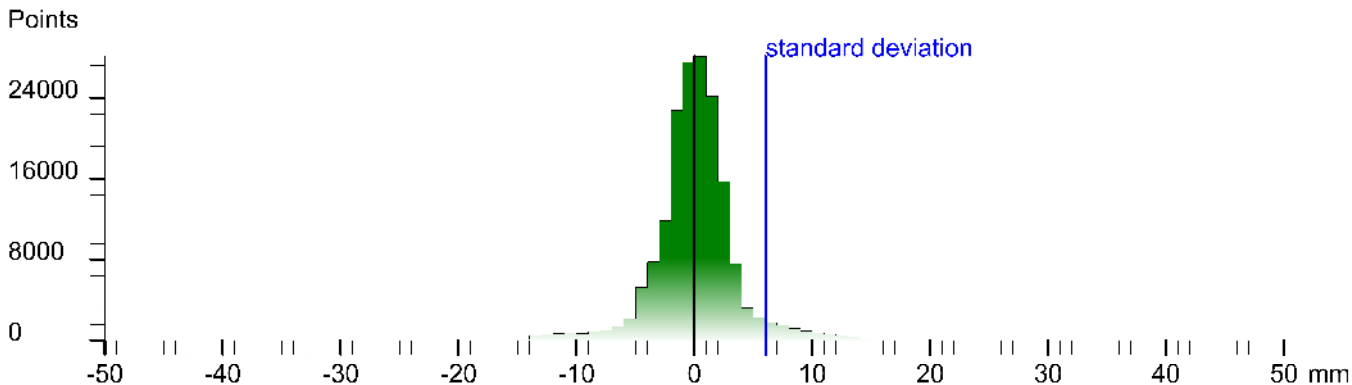
Scan position '56'

Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```
0.610835 0.791759 -0.000110 47.5049 m
-0.791760 0.610836 -0.000177 17.8092 m
-0.000074 0.000195 1.000000 0.6926 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:6.0 mm

Deviation histogram



Scan '56'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: null
Sensor
sensors: 3100 *barometer transition rotation gps
Barometer: 0.997455 bar * 32.329 m
nav translation: 7.317 m -3.5878 m 131.5389 m accuracies: 8.1057 m 8.1057 m 0.0000 m
nav rotation: 0.0000 0.0000 /2.516" accuracies: 0.0000 0.0000 /s.0000
upside-down: no
GPS lat:44.943891 long:26.029885 satellites:4 height:190.7m hddo:2.9 vddcp:8.3m hacc:6.6-m vacc:14.0 flags:G3 's same sbrno 3D solution'
north:4977131.797 m east:423463.422 m zone:35T
Initial pre position (3-coo. tocoor)
0.304 0.953 0.000 41.015
-0.953 0.304 0.000 -23.242
0.000 0.000 1.000 -53.123
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '58'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

Registration matrix:

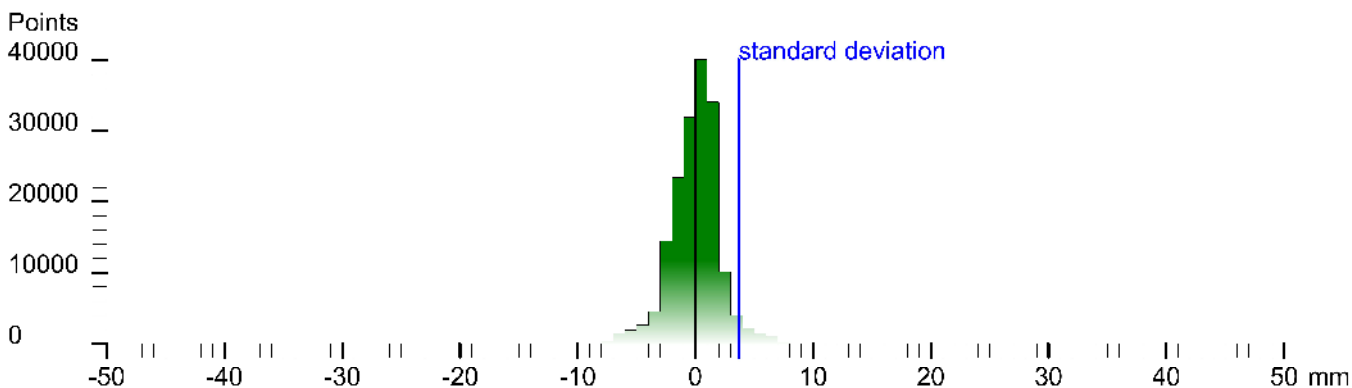
```

-0.956220  0.292649  0.000431  45.6151 m
-0.292650 -0.956222 -0.000419  4.9401 m
 0.000290 -0.000528  1.000000  0.8465 m
 0.000000  0.000000  0.000000  1.0000

```

Result registration cloud to cloud standard deviation:3.7 mm

Deviation histogram



Scan '58'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

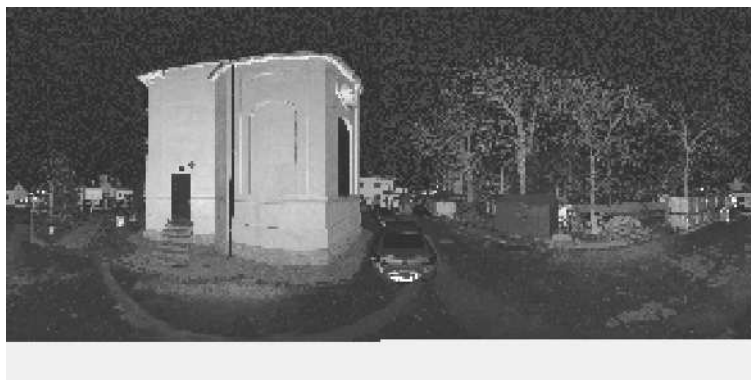
Sensor

```

sensors: 3100 *baromet or transition rotation gps
Barometer: 0.997857 bar * 30.826 m
nav translation: -3.8877 m -7.9034 m 130.6233 m accuracies: 8.1299 m 9.1299 m 0.0000 m
nav rotation: 0.0000 0.0000 * 52.6190 accuracies: 0.0000 0.0000 15.0000
upside-down: no
GPS lat: 44.943359 long: 26.029787 satellites: 5 height: 187.8m hdop: 4.3 vdcop: 5.8m hacc: 23.0m vacc: 23.0 tags: G3 *stand alone 3D solution
north: 197.7116,192 nr east: 423.457,065 m zone: 35T
Initial pre position (3coo, tocoor):
-0.888 0.460 0.000 50.606
-0.488 -0.085 0.000 -32.042
0.000 0.000 1.000 -51.088
0.000 0.000 0.000 1.000

```

Level system info: dynamic compensator available.



Scan position '59'

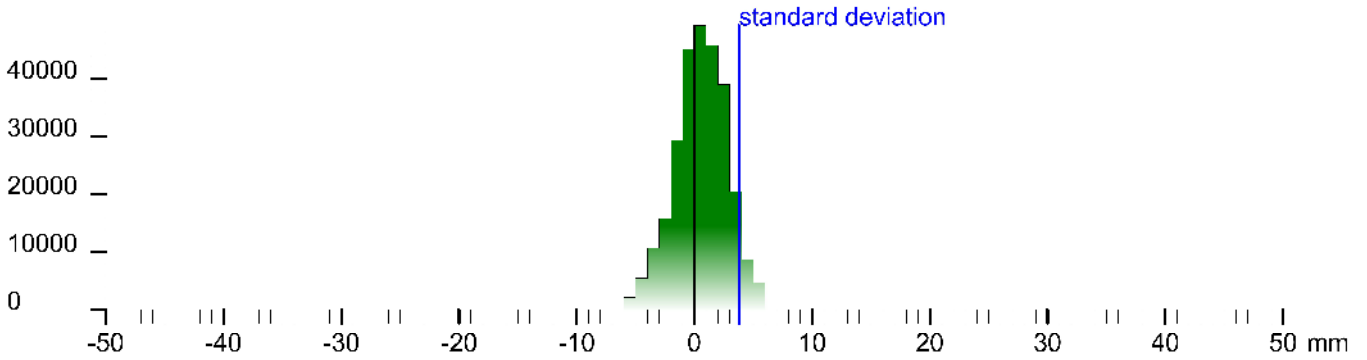
Scan position is member of group(s):
Status registration '[102h] registered with cloud to cloud'
Registration matrix:

```
-0.882883  0.469594  -0.000561  43.0719 m  
-0.469594  -0.882882  -0.000344  -2.0686 m  
-0.000657  -0.000039  1.000000  0.8766 m  
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation:3.8 mm

Deviation histogram

Points



Scan '59'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Scan on name: '59' serial: '5016-0100' firmware: '9.0.3.6562-0' scan resolution: 'High' quality: 'Normal'  
Sensor  
sensors: 3100 *barometer transition rotation gps  
Barometer: 0.997748 bar / 29.859 m  
nav translation: -3.0119 m -7.8003 m 129.13 / 2 m accuracies: 0.3362 m 0.3362 m 0.0000 m  
nav rotation: 0.0000 0.0000 -46.4020 accuracies: 0.0000 0.0000 15.0000  
upside-down: no  
GPS lat: 44.9433+4 long: 26.029757 satellites: 5 height: 181.7m hddo: 2.3 vddp: 3.0m hacc: 9.3-m vacc: 11.0 tags: G3 'stand alone 3D solution'  
north: 1977114.525 m east: 423457.037 m zone: 35T  
Initial pre position (3-coo. tocoor):  
-0.833 0.553 0.000 47.585  
-0.553 -0.033 0.000 -40.742  
0.000 0.000 1.000 -52.278  
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



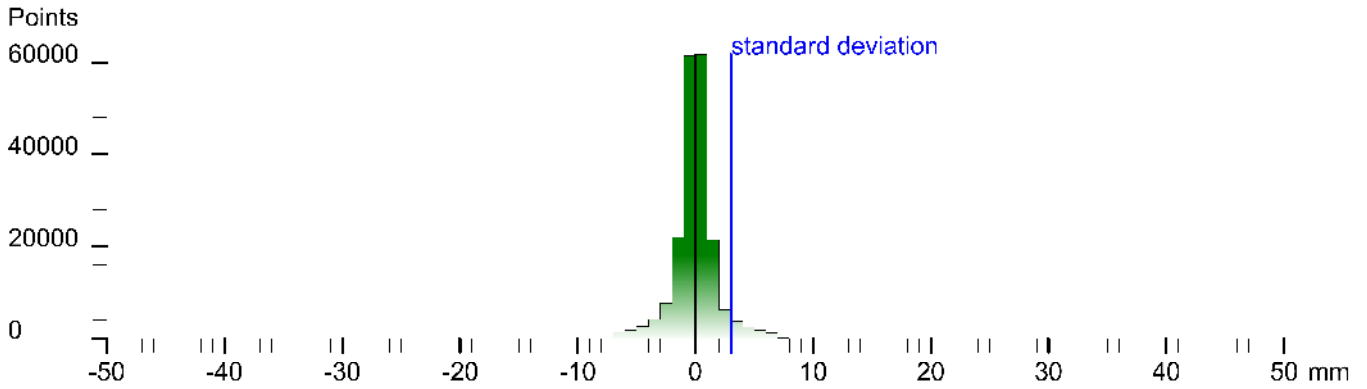
Scan position '6'

Scan position is member of group(s):
Status registration '[102h] registered with cloud to cloud'
Registration matrix:

```
0.993603  0.112935 -0.000259  11.5627 m  
-0.112936 0.993603  0.000037  2.4574 m  
0.000262 -0.000007  1.000000  0.6904 m  
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation:3.0 mm

Deviation histogram



Scan '6'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Scan comment: 'cal' LPS:blue:3.03 *max:1.4h:70 *sample:1000h:8 *v:1 *u:1 *e:1 *a:1 *b:1 *c:1 *d:1 *e:1 *f:1 *g:1 *h:1 *i:1 *j:1 *k:1 *l:1 *m:1 *n:1 *o:1 *p:1 *q:1 *r:1 *s:1 *t:1 *u:1 *v:1 *w:1 *x:1 *y:1 *z:1 *aa:1 *ab:1 *ac:1 *ad:1 *ae:1 *af:1 *ag:1 *ah:1 *ai:1 *aj:1 *ak:1 *al:1 *am:1 *an:1 *ao:1 *ap:1 *aq:1 *ar:1 *as:1 *at:1 *au:1 *av:1 *aw:1 *ax:1 *ay:1 *az:1 *ba:1 *bb:1 *bc:1 *bd:1 *be:1 *bf:1 *bg:1 *bh:1 *bi:1 *bj:1 *bk:1 *bl:1 *bm:1 *bn:1 *bo:1 *bp:1 *bq:1 *br:1 *bs:1 *bt:1 *bu:1 *bv:1 *bw:1 *bx:1 *by:1 *bz:1 *ca:1 *cb:1 *cc:1 *cd:1 *ce:1 *cf:1 *cg:1 *ch:1 *ci:1 *cj:1 *ck:1 *cl:1 *cm:1 *cn:1 *co:1 *cp:1 *cq:1 *cr:1 *cs:1 *ct:1 *cu:1 *cv:1 *cw:1 *cx:1 *cy:1 *cz:1 *da:1 *db:1 *dc:1 *dd:1 *de:1 *df:1 *dg:1 *dh:1 *di:1 *dj:1 *dk:1 *dl:1 *dm:1 *dn:1 *do:1 *dp:1 *dq:1 *dr:1 *ds:1 *dt:1 *du:1 *dv:1 *dw:1 *dx:1 *dy:1 *dz:1 *ea:1 *eb:1 *ec:1 *ed:1 *ee:1 *ef:1 *eg:1 *eh:1 *ei:1 *ej:1 *ek:1 *el:1 *em:1 *en:1 *eo:1 *ep:1 *eq:1 *er:1 *es:1 *et:1 *eu:1 *ev:1 *ew:1 *ex:1 *ey:1 *ez:1 *fa:1 *fb:1 *fc:1 *fd:1 *fe:1 *ff:1 *fg:1 *fh:1 *fi:1 *fj:1 *fk:1 *fl:1 *fm:1 *fn:1 *fo:1 *fp:1 *fq:1 *fr:1 *fs:1 *ft:1 *fu:1 *fv:1 *fw:1 *fx:1 *fy:1 *fz:1 *ga:1 *gb:1 *gc:1 *gd:1 *ge:1 *gf:1 *gg:1 *gh:1 *gi:1 *gj:1 *gk:1 *gl:1 *gm:1 *gn:1 *go:1 *gp:1 *gq:1 *gr:1 *gs:1 *gt:1 *gu:1 *gv:1 *gw:1 *gx:1 *gy:1 *gz:1 *ha:1 *hb:1 *hc:1 *hd:1 *he:1 *hf:1 *hg:1 *hh:1 *hi:1 *hj:1 *hk:1 *hl:1 *hm:1 *hn:1 *ho:1 *hp:1 *hq:1 *hr:1 *hs:1 *ht:1 *hu:1 *hv:1 *hw:1 *hx:1 *hy:1 *hz:1 *ia:1 *ib:1 *ic:1 *id:1 *ie:1 *if:1 *ig:1 *ih:1 *ii:1 *ij:1 *ik:1 *il:1 *im:1 *in:1 *io:1 *ip:1 *iq:1 *ir:1 *is:1 *it:1 *iu:1 *iv:1 *iw:1 *ix:1 *iy:1 *iz:1 *ja:1 *jb:1 *jc:1 *jd:1 *je:1 *jf:1 *jg:1 *jh:1 *ji:1 *jj:1 *jk:1 *jl:1 *jm:1 *jn:1 *jo:1 *jp:1 *jq:1 *jr:1 *js:1 *jt:1 *ju:1 *jv:1 *jw:1 *jx:1 *jy:1 *jz:1 *ka:1 *kb:1 *kc:1 *kd:1 *ke:1 *kf:1 *kg:1 *kh:1 *ki:1 *kj:1 *kk:1 *kl:1 *km:1 *kn:1 *ko:1 *kp:1 *kq:1 *kr:1 *ks:1 *kt:1 *ku:1 *kv:1 *kw:1 *kx:1 *ky:1 *kz:1 *la:1 *lb:1 *lc:1 *ld:1 *le:1 *lf:1 *lg:1 *lh:1 *li:1 *lj:1 *lk:1 *ll:1 *lm:1 *ln:1 *lo:1 *lp:1 *lq:1 *lr:1 *ls:1 *lt:1 *lu:1 *lv:1 *lw:1 *lx:1 *ly:1 *lz:1 *ma:1 *mb:1 *mc:1 *md:1 *me:1 *mf:1 *mg:1 *mh:1 *mi:1 *mj:1 *mk:1 *ml:1 *mm:1 *mn:1 *mo:1 *mp:1 *mq:1 *mr:1 *ms:1 *mt:1 *mu:1 *mv:1 *mw:1 *mx:1 *my:1 *mz:1 *na:1 *nb:1 *nc:1 *nd:1 *ne:1 *nf:1 *ng:1 *nh:1 *ni:1 *nj:1 *nk:1 *nl:1 *nm:1 *no:1 *np:1 *nq:1 *nr:1 *ns:1 *nt:1 *nu:1 *nv:1 *nw:1 *nx:1 *ny:1 *nz:1 *oa:1 *ob:1 *oc:1 *od:1 *oe:1 *of:1 *og:1 *oh:1 *oi:1 *oj:1 *ok:1 *ol:1 *om:1 *on:1 *oo:1 *op:1 *oq:1 *or:1 *os:1 *ot:1 *ou:1 *ov:1 *ow:1 *ox:1 *oy:1 *oz:1 *pa:1 *pb:1 *pc:1 *pd:1 *pe:1 *pf:1 *pg:1 *ph:1 *pi:1 *pj:1 *pk:1 *pl:1 *pm:1 *pn:1 *po:1 *pp:1 *pq:1 *pr:1 *ps:1 *pt:1 *pu:1 *pv:1 *pw:1 *px:1 *py:1 *pz:1 *qa:1 *qb:1 *qc:1 *qd:1 *qe:1 *qf:1 *qg:1 *qh:1 *qi:1 *qj:1 *qk:1 *ql:1 *qm:1 *qn:1 *qo:1 *qp:1 *qq:1 *qr:1 *qs:1 *qt:1 *qu:1 *qv:1 *qw:1 *qx:1 *qy:1 *qz:1 *ra:1 *rb:1 *rc:1 *rd:1 *re:1 *rf:1 *rg:1 *rh:1 *ri:1 *rj:1 *rk:1 *rl:1 *rm:1 *rn:1 *ro:1 *rp:1 *rq:1 *rr:1 *rs:1 *rt:1 *ru:1 *rv:1 *rw:1 *rx:1 *ry:1 *rz:1 *sa:1 *sb:1 *sc:1 *sd:1 *se:1 *sf:1 *sg:1 *sh:1 *si:1 *sj:1 *sk:1 *sl:1 *sm:1 *sn:1 *so:1 *sp:1 *sq:1 *sr:1 *ss:1 *st:1 *su:1 *sv:1 *sw:1 *sx:1 *sy:1 *sz:1 *ta:1 *tb:1 *tc:1 *td:1 *te:1 *tf:1 *tg:1 *th:1 *ti:1 *tj:1 *tk:1 *tl:1 *tm:1 *tn:1 *to:1 *tp:1 *tq:1 *tr:1 *ts:1 *tt:1 *tu:1 *tv:1 *tw:1 *tx:1 *ty:1 *tz:1 *ua:1 *ub:1 *uc:1 *ud:1 *ue:1 *uf:1 *ug:1 *uh:1 *ui:1 *uj:1 *uk:1 *ul:1 *um:1 *un:1 *uo:1 *up:1 *uq:1 *ur:1 *us:1 *ut:1 *uu:1 *uv:1 *uw:1 *ux:1 *uy:1 *uz:1 *va:1 *vb:1 *vc:1 *vd:1 *ve:1 *vf:1 *vg:1 *vh:1 *vi:1 *vj:1 *vk:1 *vl:1 *vm:1 *vn:1 *vo:1 *vp:1 *vq:1 *vr:1 *vs:1 *vt:1 *vu:1 *vv:1 *vw:1 *vx:1 *vy:1 *vz:1 *wa:1 *wb:1 *wc:1 *wd:1 *we:1 *wf:1 *wg:1 *wh:1 *wi:1 *wj:1 *wk:1 *wl:1 *wm:1 *wn:1 *wo:1 *wp:1 *wq:1 *wr:1 *ws:1 *wt:1 *wu:1 *wv:1 *ww:1 *wx:1 *wy:1 *wz:1 *xa:1 *xb:1 *xc:1 *xd:1 *xe:1 *xf:1 *xg:1 *xh:1 *xi:1 *xj:1 *xk:1 *xl:1 *xm:1 *xn:1 *xo:1 *xp:1 *xq:1 *xr:1 *xs:1 *xt:1 *xu:1 *xv:1 *xw:1 *xx:1 *xy:1 *xz:1 *ya:1 *yb:1 *yc:1 *yd:1 *ye:1 *yf:1 *yg:1 *yh:1 *yi:1 *yj:1 *yk:1 *yl:1 *ym:1 *yn:1 *yo:1 *yp:1 *yq:1 *yr:1 *ys:1 *yt:1 *yu:1 *yv:1 *yw:1 *yx:1 *yy:1 *yz:1 *za:1 *zb:1 *zc:1 *zd:1 *ze:1 *zf:1 *zg:1 *zh:1 *zi:1 *zj:1 *zk:1 *zl:1 *zm:1 *zn:1 *zo:1 *zp:1 *zq:1 *zr:1 *zs:1 *zt:1 *zu:1 *zv:1 *zw:1 *zx:1 *zy:1 *zz:1
```

Level system info: dynamic compensator available.



Scan position '60'

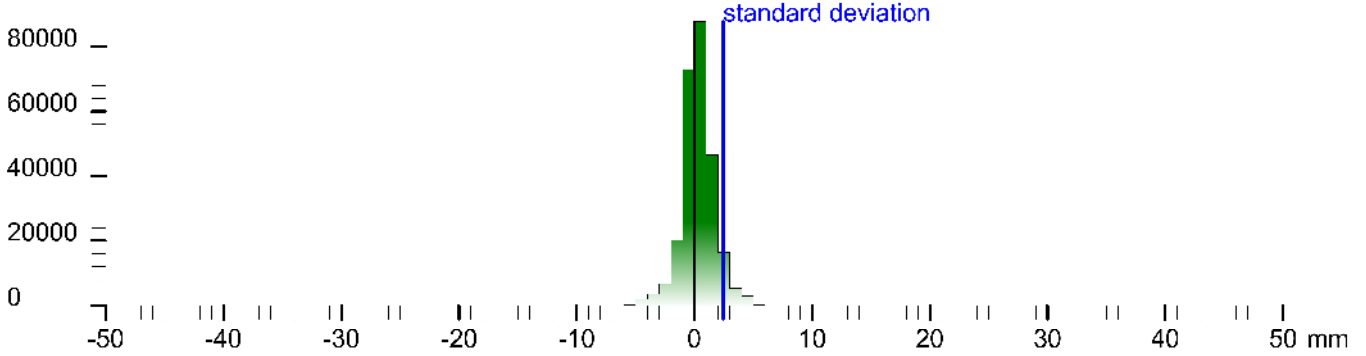
Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```
-0.929941  0.367709 -0.000281 39.1401 m
-0.367709 -0.929942 -0.000404 -2.3132 m
-0.000410 -0.000272  1.000000  0.6334 m
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation:2.4 mm

Deviation histogram

Points



Scan '60'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata Value
comment
operator

```
Scan command: cd "/usr/bin" && ls -l |> cat |> grep "Z+F" |> cat |> sed -e 's/ / /' |> sed -e 's/\"/>

```

Level system info: dynamic compensator available.



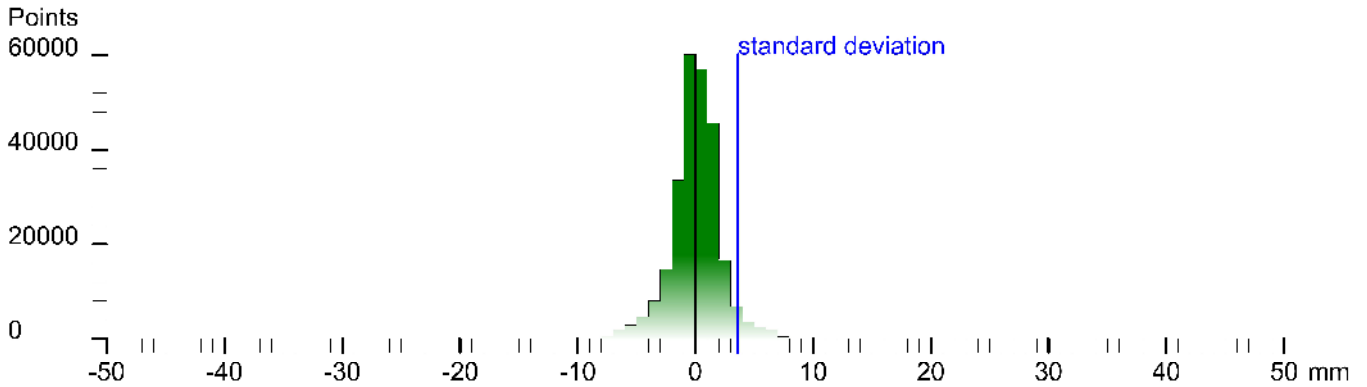
Scan position '61'

Scan position is member of group(s):
Status registration '[102h] registered with cloud to cloud'
Registration matrix:

```
0.789388 0.613895 -0.000038 37.3033 m  
-0.613893 0.789389 -0.000618 -6.4796 m  
-0.000348 0.000510 1.000001 0.1538 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:3.6 mm

Deviation histogram



Scan '61'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Sensor: 3100 * barometric transition rotation gps  
Barometer: 1.000859 bar * 03.87 m  
nav translation: 0.0000 m 0.0000 m 102.87 * 3 m accuracies: 5.1000 m 5.1000 m 3.0001 m  
nav rotation: 0.0000 0.0000 0.0000 0.0000 0.0000 0.0000 0.0000 0.0000 0.0000  
upside-down: no  
GPS lat: 44.943382 long: 26.029648 satellites: 5 height: 177.2m hdop: 9.2 vdcpr: 12.0m hacc: 21.0m vacc: 23.0m flags: G3 'stand alone 3D solution'  
north: 1977118.866 m east: 423416.11 m zone: 35T  
Initial pre position (3-coor):  
0.611 0.585 0.000 44.19°  
-0.585 0.611 0.000 -43.035  
0.000 0.000 1.000 -78.84C  
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '62'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

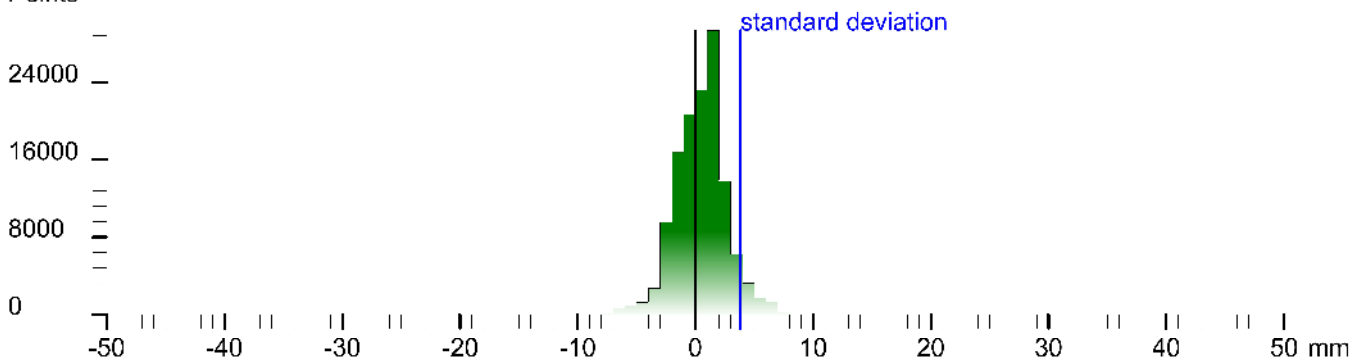
Registration matrix:

```
-0.722649 -0.691217 -0.000212 33.8377 m
0.691216 -0.722649 -0.000780 -0.4346 m
0.000385 -0.000709 1.000000 1.0323 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:3.8 mm

Deviation histogram

Points



Scan '62'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: null
Sensor
sensors: 3100 *barome or transition rotation gps
Barometer: 1.000844 bar * 03.73 * m
nav translation: -1.9028 m 2.6579 m 103.372 m accuracies: 7.5976 m 7.9946 m 0.0000 m
nav rotation: 0.0000 0.0000 * 86.9291 accuracies: 0.0000 0.0000 16.0000
upside-down: no
GPS lat:44.943099 long:26.030686 satellites:3 height:187.2m hhdoo:20.1 vdoor:1.0m hacc:5.2m vacc:12.0 tags:G2 *stand alone 2D solution
north:1977378.754 m east:423527.062 m zone:35T
Initial pre position (3-coo. tocoor)
-0.993 -0.127 0.000 39.29C
0.21 -0.993 0.000 -41.203
0.000 0.000 1.000 -76.395
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '63'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

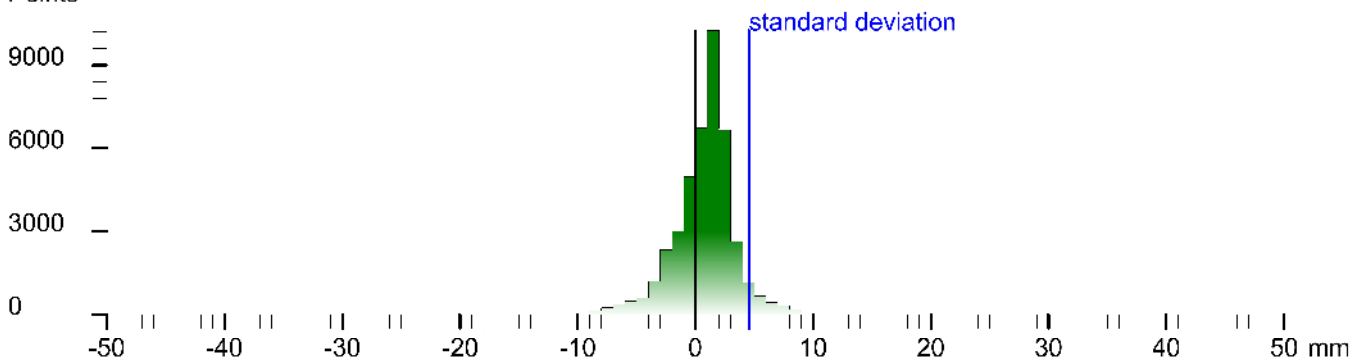
Registration matrix:

-0.227911	0.973684	-0.000727	33.6364 m
-0.973683	-0.227912	-0.000482	0.2367 m
-0.000635	0.000598	1.000001	0.2317 m
0.000000	0.000000	0.000000	1.0000

Result registration cloud to cloud standard deviation:4.6 mm

Deviation histogram

Points



Scan '63'

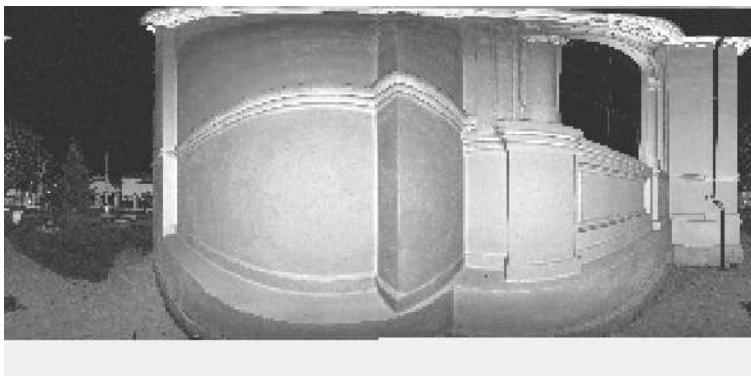
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

Sensor: 3096 *barometric transition rotation*
Barometer: 1.000039 bar / 02.894 m
nav translation: 0.0000 m 0.0000 m 102.0893 m accuracies: 5.2132 m 5.2132 m 0.0001 m
nav rotation: 0.0000 0.0000 64.7669 accuracies: 0.0000 0.0000 15.0000
upside-down: no
Initial pre position: (Girdoor)
0.426 0.905 0.000 39.290
-0.905 0.426 0.000 -41.282
0.000 0.000 1.000 -79.023
0.000 0.000 0.000 1.000

Level system info: dynamic compensator available.



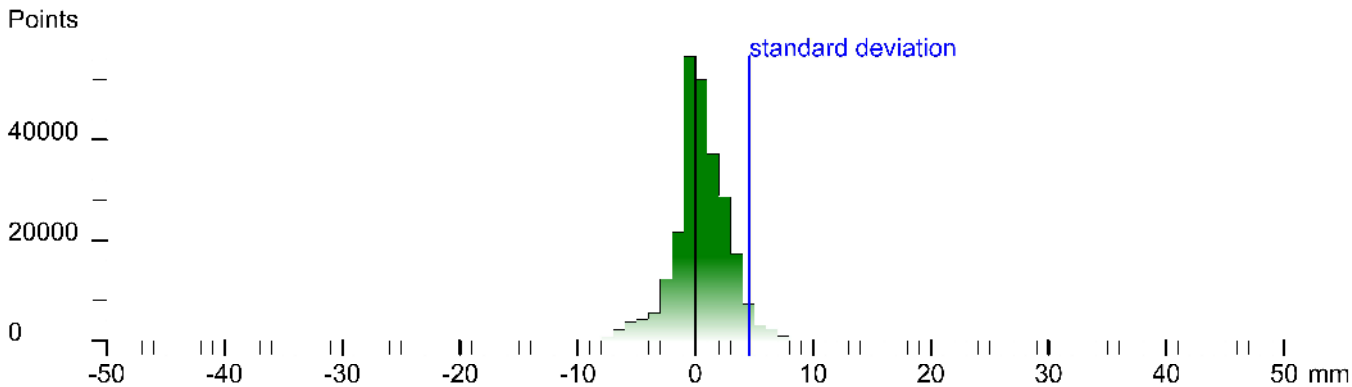
Scan position '64'

Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```
-0.938851 -0.344327 0.000277 30.7564 m
0.344326 -0.938849 -0.001139 -5.9637 m
0.000650 -0.000973 0.999999 0.1191 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:4.6 mm

Deviation histogram



Scan '64'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: full 1.938851 -0.344327 0.000277 30.7564 m
Sensor
sensors: 3100 *barome or transition rotation gps
Barometer: 1.001088 bar * 01.748 m
nav translation: 2.3287 m -0.9730 m 102.0930 m accuracies: 8.9326 m 8.9326 m 0.0000 m
nav rotation: 0.0000 0.0000 * 92.0/64 accuracies: 0.0000 0.0000 15.0000
upside-down: no
GPS lat:44.943291 long:26.029506 satellites:5 height:189.9m hdop:4.6 vdcop:7.2m hacc: 0.0m vacc:11.0 fbsgs:G3 *stand alone 3D solution
north:4977108.744 m east:423411.926 m zone:35T
Initial pre position (3-coo. tocoor)
-0.976 -0.218 0.000 41.819
0.218 -0.976 0.000 -48.256
0.000 0.000 1.000 -79.622
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '65'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

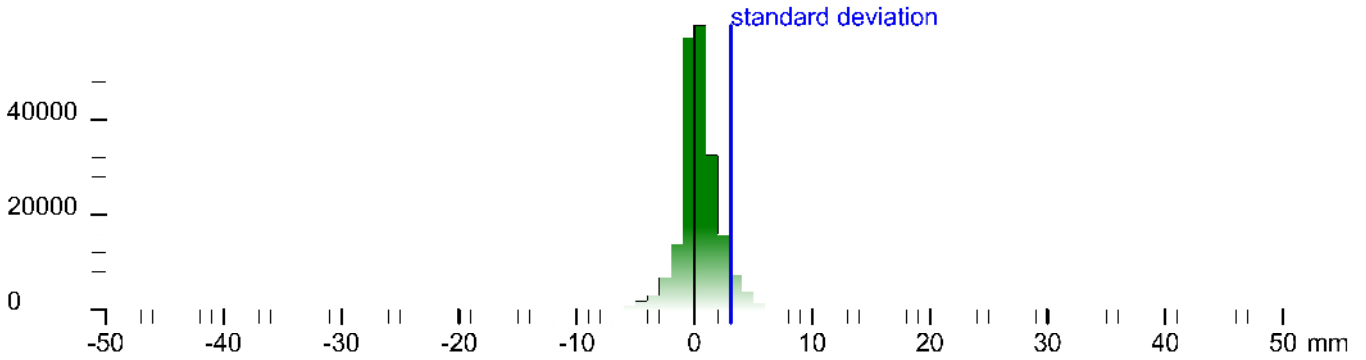
Registration matrix:

```
-0.482781 -0.875743 -0.000146 26.0163 m
 0.875740 -0.482781 -0.000665 -6.7286 m
 0.000510 -0.000449 1.000000 0.1165 m
 0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 3.1 mm

Deviation histogram

Points



Scan '65'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

Scan on [name: full 1308x1200] [angle: 148.78] [radius: 95] [height: 8.7] m [width: 8.7] m [position: 0.0] [compensator: none] [status: 27] source: PointCloud - scan area: 166.11m x 166.11m for 120° and 130°

Sensor:

sensors: 3100 * barome or transition rotation gps

Barometer: 1.001151 bar 101.2 °F

nav translation: -2.8787 m -0.3046 m 100.6561 m accuracies: 0.5535 m 0.5535 m 0.0000 m

nav rotation: 0.0000 0.0000 256.469 / accuracies: 0.0000 0.0000 1s.0000

upside-down: no

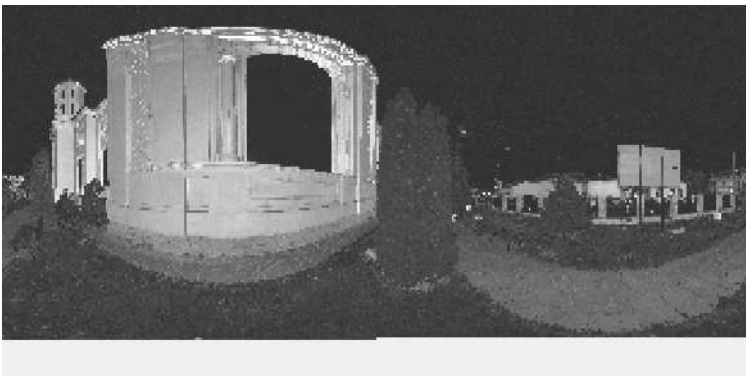
GPS lat: 44.943285 long: 26.029582 satellites: 4 height: 107.1m hdop: 3.3 vdcop: 5.3m hacc: 1.0m vacc: 13.0 ft/sgs: G3 *stand alone 3D solution'

North: 1977106.234 m east: 423439.187 m zone: 35T

Initial pre position (3-coor):

```
-0.552 -0.834 0.000 38.741
 0.834 -0.552 0.000 -46.321
 0.000 0.000 1.000 -51.058
 0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '66'

Scan position is member of group(s):

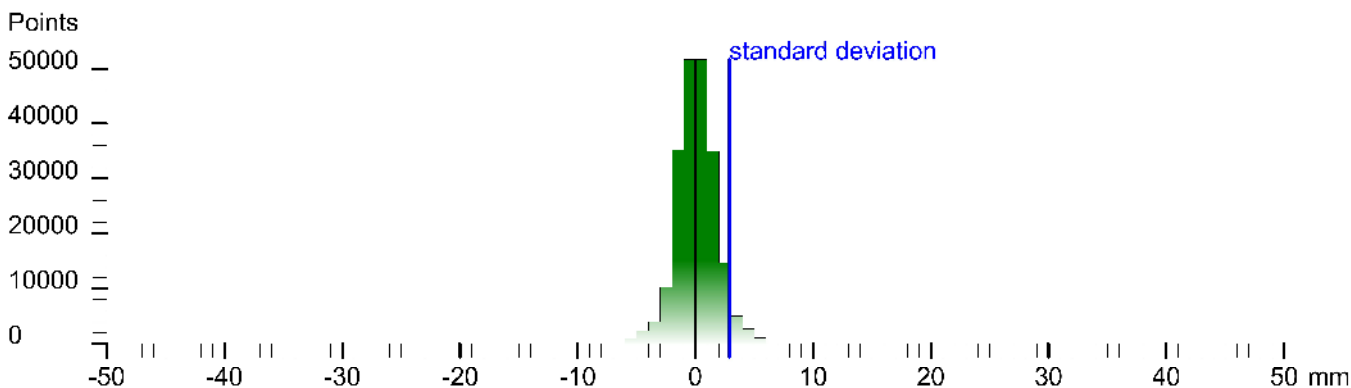
Status registration '[102h] registered with cloud to cloud'

Registration matrix:

```
0.160934 -0.986966 -0.000690 21.6820 m
0.986965 0.160933 -0.000633 -6.6196 m
0.000734 -0.000580 1.000000 0.1712 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:2.9 mm

Deviation histogram



Scan '66'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: null
Sensor
sensors: 3100 *barome or transition rotation gps
Barometer: 1.001243 bar *00.44 m
nav translation: -2.8906 m 1.3932 m 100.3580 m accuracies: 0.7116 m 0.7116 m 0.0032 m
nav rotation: 0.0000 0.0000 2/9.5692 accuracies: 0.0000 0.0000 1s.0000
upside-down: no
GPS lat:44.943264 long:26.029488 satellites:4 height:107.8m hdop:3.2 vdcpx:6.8m hacc:2.0m vacc:1.4 flags:G3 's are alone 3D solution'
north:1977105.860 m east:423433.313 m zone:35T
Initial pre position (3-coo. tocoor)
0.986 -0.986 0.000 35.850
0.986 0.166 0.000 -48.907
0.000 0.000 1.000 -51.353
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



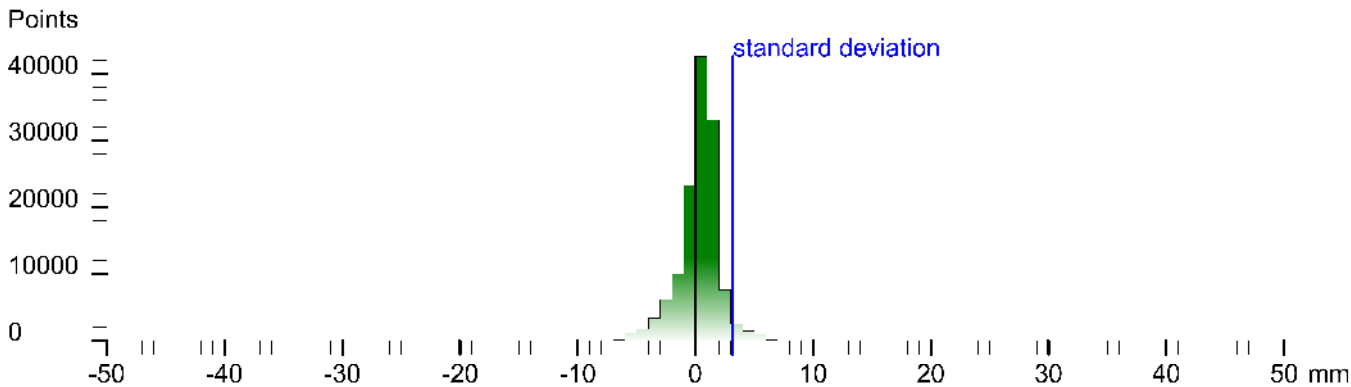
Scan position '68'

Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```
-0.929824  0.368006  0.000169  14.6055 m
-0.368007 -0.929823 -0.000322 -4.9079 m
0.000039 -0.000360  1.000000  0.2130 m
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation:3.2 mm

Deviation histogram



Scan '68'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: full 1.908x0.303 m angle: 1.48:78:58 azimut: 92:49:51 tilt: 8:16:11 camera: Z+F Imager 5016 camera serial: 5016-0100 camera firmware: 9.0.3.6562-0 scan date: 2024-04-18 11:27:46:1940
Sensor
sensors: 3100 *barome or transition rotation gps
Barometer: 1.001220 bar * 00.833 m
nav translation: -2.3760 m -2.4217 m 100.282 m accuracies: 6.9049 m 6.8049 m 0.0000 m
nav rotation: 0.0000 0.0000 * 48.6:44 accuracies: 0.0000 0.0000 1s:0.0000
upside-down: no
GPS lat:44.943291 long:26.029436 satellites:4 height:190.1m hdop:6.4 vdcp:5.0m hacc: 6.0m vacc:14.0 tags:G3 *stand alone 3D solution
Initial pre position (3-coo. tocoo):
-0.850 0.570 0.000 30.084
-0.520 -0.054 0.000 -48.130
0.000 0.000 1.000 -51.428
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '69'

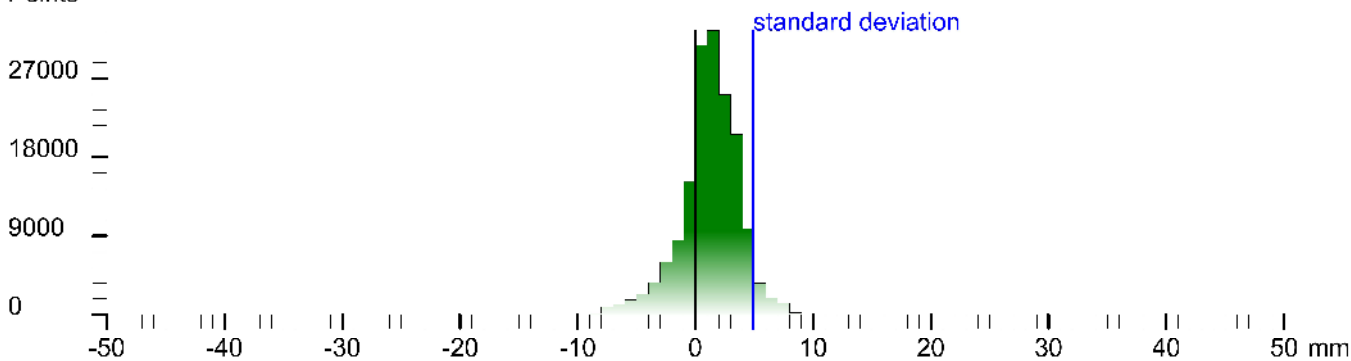
Scan position is member of group(s):
Status registration '[102h] registered with cloud to cloud'
Registration matrix:

```
-0.876302 -0.481763 0.000034 11.9813 m  
0.481762 -0.876301 -0.000764 -10.2671 m  
0.000396 -0.000653 1.000000 0.2279 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 4.9 mm

Deviation histogram

Points



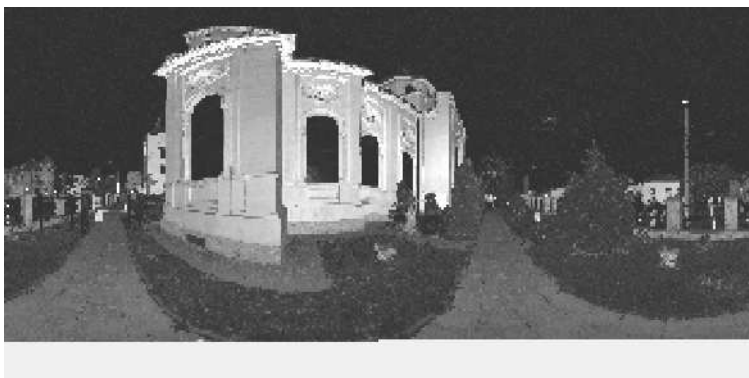
Scan '69'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

Sensor: 3100 * barometric transition rotation gps
Barometer: 1.001180 bar 100.87 m
nav translation: -1.5086 m -2.5912 m 100.6753 m accuracies: 7.7210 m 7.7210 m 0.0000 m
nav rotation: 0.0000 0.0000 203.006 / accuracies: 0.0000 0.0000 1s.0000
upside-down: no
GPS lat: 44.9432+11 long: 26.029381 satellites: 5 height: 102.1m hdop: 2.4 vdcop: 3.0m htacc: 6.3-m vdcop: 7.4 flags: G3 'stand alone 3D solution'
north: 1977103 / 38 m east: 423421.856 m zone: 35T
Initial pre position (3-coor):
-0.990 -0.38 0.000 25.574
0.381 -0.920 0.000 -46.721
0.000 0.000 1.000 -51.036
0.000 0.000 0.000 1.000

Level system info: dynamic compensator available.



Scan position '7'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

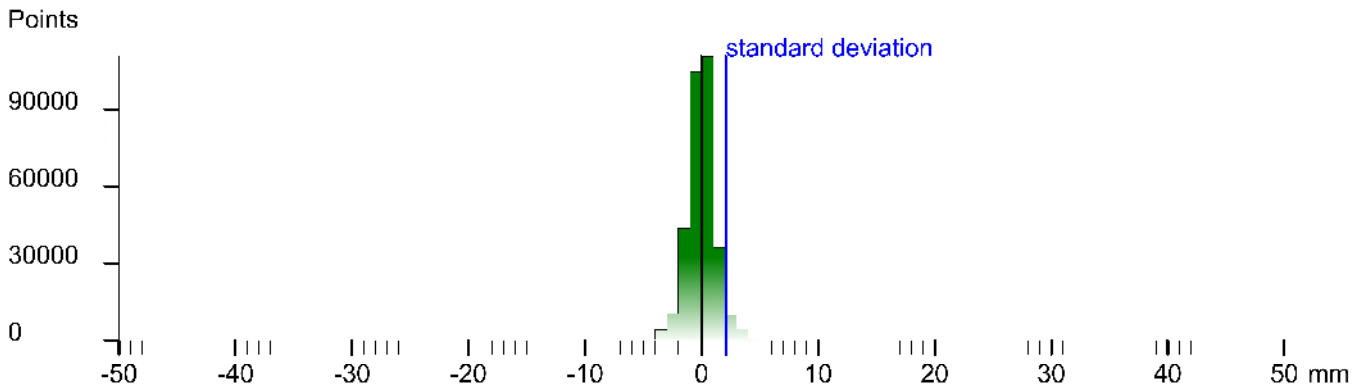
Registration matrix:

```

0.973831  0.227279  -0.000167  10.5348 m
-0.227280 0.973830  -0.000084  -1.9758 m
0.000144  0.000119  0.999999  0.6769 m
0.000000  0.000000  0.000000  1.0000
    
```

Result registration cloud to cloud standard deviation: 2.1 mm

Deviation histogram



Scan '7'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```

Scan comment: '148846133' - '148846133' - '148846133' - '148846133' - '148846133' - '148846133' - '148846133' - '148846133' - '148846133' - '148846133'
Sensor
sensors: 3096 "barometric transition rotation"
Barometer: 0.991903 bar "79.25" m
nav translation: -3.89/2 m -3.4789 m 178.706 m accuracies: 6.9152 m 6.9152 m 0.0000 m
nav rotation: 0.0000 0.0000 "2.2490 accuracies: 0.0000 0.0000 0.0000
upside-down: no
Initial position (Girdoor)
0.977 0.212 0.000 -5.335
-0.212 0.977 0.000 -1.597
0.000 0.000 1.000 -2.071
0.000 0.000 0.000 1.000
    
```

Level system info: dynamic compensator available.



Scan position '70'

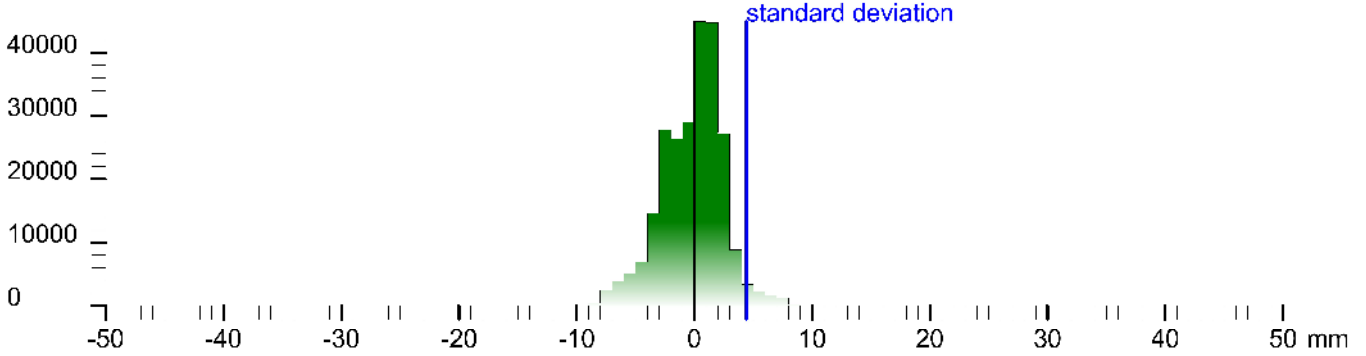
Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```
-0.998998 -0.044775 -0.000111 7.0797 m
0.044773 -0.998997 -0.000509 -11.6061 m
-0.000089 -0.000513 1.000000 0.2407 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:4.4 mm

Deviation histogram

Points



Scan '70'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata Value comment operator

```
Scan comment: null L928332-0331-manifest-148-707-scans-707-qm-B016-0100-0100-Z+F-IMAGER-5016-0100-9.0.3.6562-0-20230910-16:04:18-1610-101-101-101-101-101
Sensor
sensors: 3100 *barometric transition rotation gps
Barometer: 1.001195 bar 100.846 m
nav translation: -2.7051 m -1.7057 m 100.6080 m accuracies: 0.0857 m 0.0857 m 0.0009 m
nav rotation: 0.0000 0.0000 0.0000 // axes accuracies: 0.0000 0.0000 1s,0.0000
upside-down: no
GPS lat:44.9432+1 long:26.02932+ satellites:5 height:189.3m hddoc:2.3 vdcop:3.9m hacc:5.2-m vacc:10.0 flags:G3 's:anc s:nc 3D solution'
north:4977103.793 m east:423420.342 m zone:35T
Initial pre position (3..toor)
-0.9989 0 0-3 0.000 000.808
-0.043 -0.009 0.000 -50.187
0.000 0.000 1.000 -51.107
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '71'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

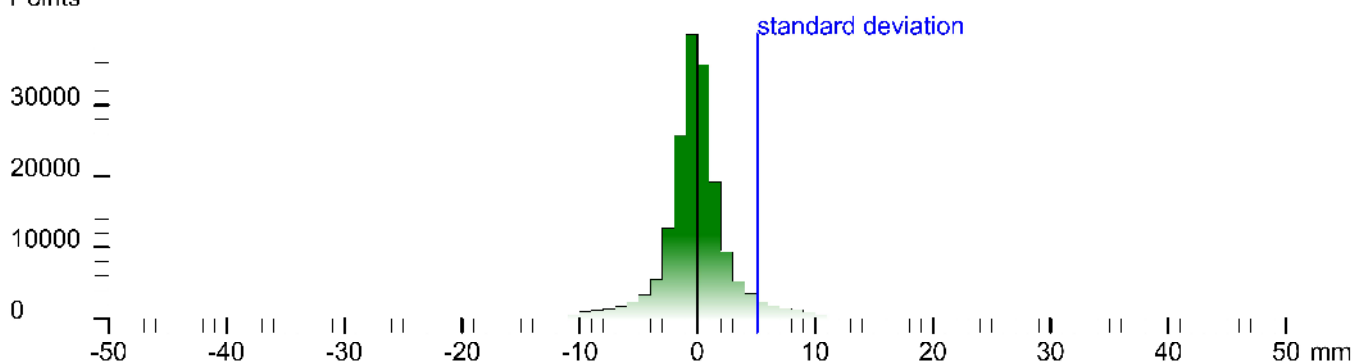
Registration matrix:

0.018352	-0.999832	-0.000312	3.7140 m
0.999831	0.018351	-0.000521	-12.2761 m
0.000526	-0.000304	1.000000	0.6466 m
0.000000	0.000000	0.000000	1.0000

Result registration cloud to cloud standard deviation:5.1 mm

Deviation histogram

Points



Scan '71'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Sensor: 3100 * barometric transition rotation gps
Barometer: 1.001145 bar 101.269 m
nav translation: -2.6574 m 2.2773 m 100.2780 m accuracies: 0.5829 m 0.9829 m 0.0001 m
nav rotation: 0.0000 0.0000 266.1453 accuracies: 0.0000 0.0000 16.0000
upside-down: no
GPS lat: 44.943226 long: 26.029276 satellites: 5 height: 188.4m hdop: 2.1 vdop: 4.8m hacc: 5.3m vacc: 0.3 flags: G3 'stand alone 3D solution'
north: 197.7101, east: 423.476, zero: 35T
Initial pre position (3-coor):
-0.067 -0.896 0.000 70.15°
0.990 -0.067 0.000 -47.31°
0.000 0.000 1.000 -51.18°
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



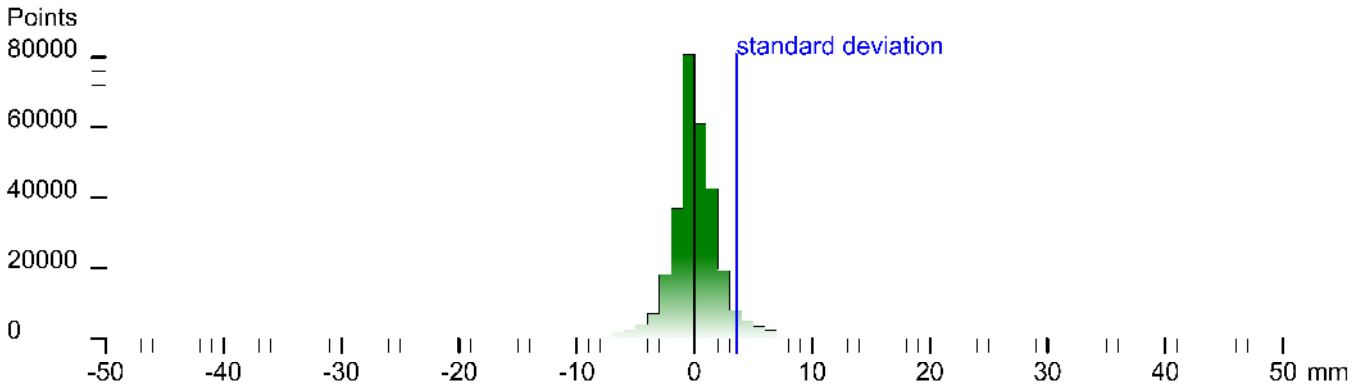
Scan position '72'

Scan position is member of group(s):
Status registration '[102h] registered with cloud to cloud'
Registration matrix:

0.999589	-0.028695	-0.000157	-0.3190 m
0.028695	0.999589	-0.000081	-5.4256 m
0.000160	0.000076	1.000000	0.2400 m
0.000000	0.000000	0.000000	1.0000

Result registration cloud to cloud standard deviation:3.6 mm

Deviation histogram



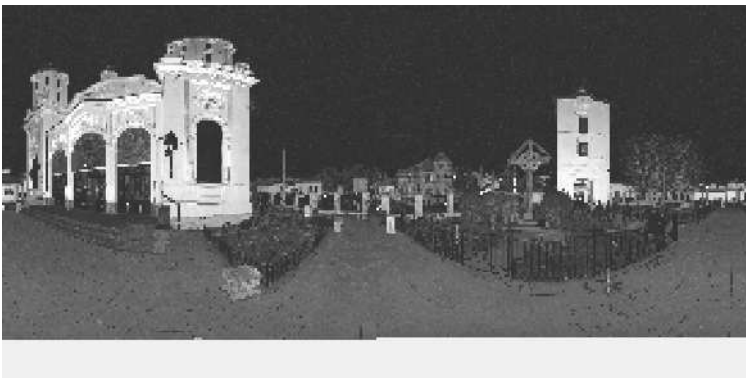
Scan '72'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: full 100bar 203° elevation 148:72 scanner '72' type 'Z+F' serial '5016-0100' firmware '9.0.3.6562-0' model '5016-0100' position: '47°46'18"N' '12°46'18"E' format '204x1024'
Sensor
sensors: 3100 * barometer transition rotation gps
Barometer: 1.001259 bar * 00.304 m
nav translation: -3.1037 m 8.2127 m 100.0368 m accuracies: 9.2776 m 9.2746 m 0.0000 m
nav rotation: 0.0000 0.0000 0.0000 accuracies: 0.0000 0.0000 1s:0.0000
upside-down: no
GPS lat:44.943283 long:26.029346 satellites:3 height:189.6m hhdop:2.5 vhdop:1.0m hacc:25.0m vacc:7.0 flags:G2's are above 2D solution'
north:4977108.132 m east:423422.203 m zone:35T
Initial pre position (3o.o.coor):
0.999 -0.033 0.000 0.000 0.048
0.033 0.999 0.000 -33.701
0.000 0.000 1.000 -51.625
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '73'

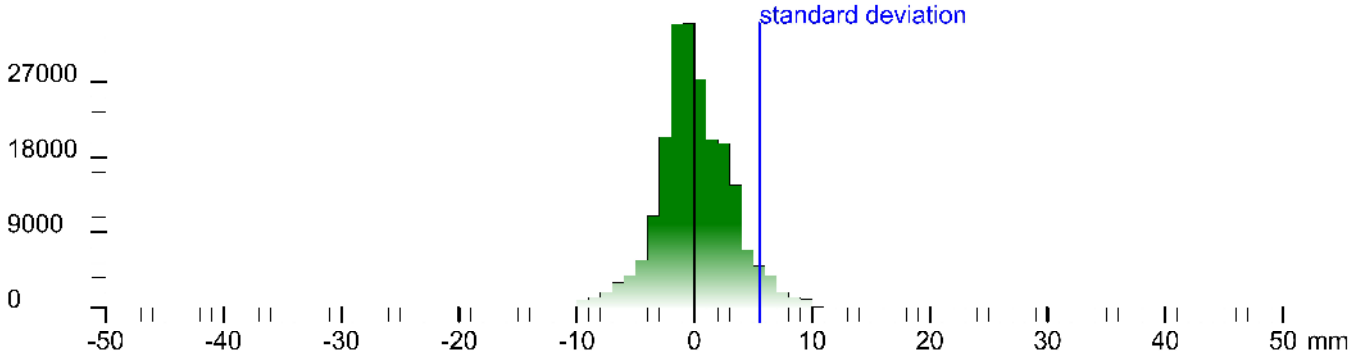
Scan position is member of group(s):
Status registration '[102h] registered with cloud to cloud'
Registration matrix:

```
-0.691111 0.722750 -0.000405 -7.9867 m  
-0.722750 -0.691111 -0.000084 -12.0772 m  
-0.000341 0.000235 1.000000 0.9119 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:5.5 mm

Deviation histogram

Points



Scan '73'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
Scan resolution 'High' quality 'Normal'

Metadata Value

comment	operator
---------	----------

```
Sensor: 3100 * barometer transition rotation gps  
Barometer: 1.001192 bar 100.872 m  
nav translation: 0.656 m -1.397 m 100.2231 m accuracies: 7.3087 m 7.3087 m 0.000 m  
nav rotation: 0.0000 0.0000 -08.7726 accuracies: 0.0000 0.0000 1s.0000  
upside-down: no  
GPS lat:44.943256 long:26.029144 satellites:5 height:185.1m hhdop:2.1 vdop:2.3m hacc:5.2m vacc:8.7 flags:G3 'stand alone 3D solution'  
north:4977105.357 m east:423406.217 m zone:35T  
Initial pre position (3-coo. tocoor)  
-0.322 0 9+7 0.000 20.213  
-0.347 -0.322 0.000 -44.035  
0.000 0.000 1.000 -51.488  
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '74'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

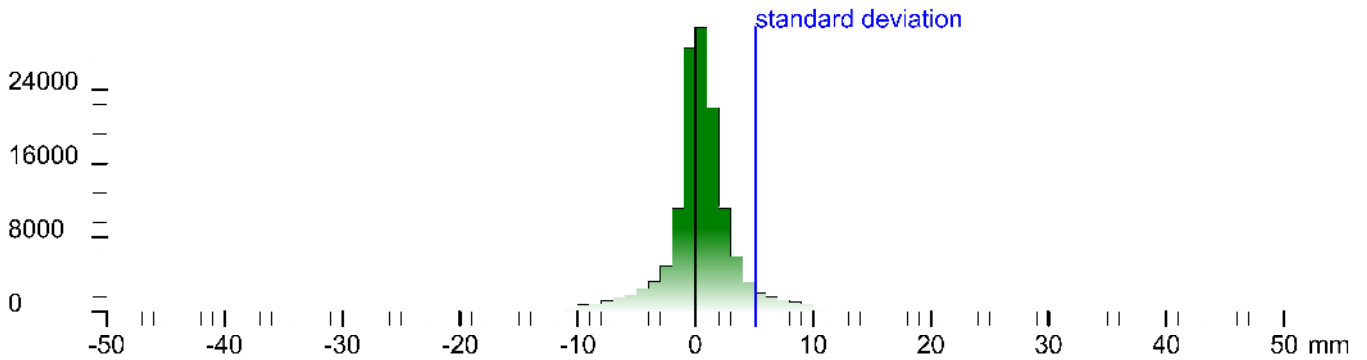
Registration matrix:

```
0.060768 -0.998152 -0.000669 -17.4753 m
0.998152 0.060766 0.000001 -11.1000 m
0.000038 -0.000669 1.000000 0.9619 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:5.1 mm

Deviation histogram

Points



Scan '74'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: full 1.908x0.303 m angle: 1.48:74' sensor: 74' type: 'Z+F IMAGER 5016' serial: '5016-0100' firmware: '9.0.3.6562-0' scan resolution: 'High' quality: 'Normal' registration: 'cloud to cloud' standard deviation: '5.1 mm' points: '24744'
Sensor
sensors: 3100 *barometer transition rotation gps
Barometer: 1.001262 bar * 00.279 m
nav translation: -2.3987 m -10.3589 m 99.9453 m accuracies: 10./551 m 10.4551 m 0.0002 m
nav rotation: 0.0000 0.0000 2/9.8/64 accuracies: 0.0000 0.0000 1s.0000
upside-down: no
GPS lat:44.943256 long:26.029013 satellites:5 height:102.0m hddos:*.5 vddcp:4.4m hacc:4.1 m vacc:11.0 tags:G3 'stand alone 3D solution'
Initial pre position (3-co. tocor):
0.77 -0.985 0.000 -71.919
0.965 0.172 0.000 -47.431
0.000 0.000 1.000 -51.766
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '75'

Scan position is member of group(s):

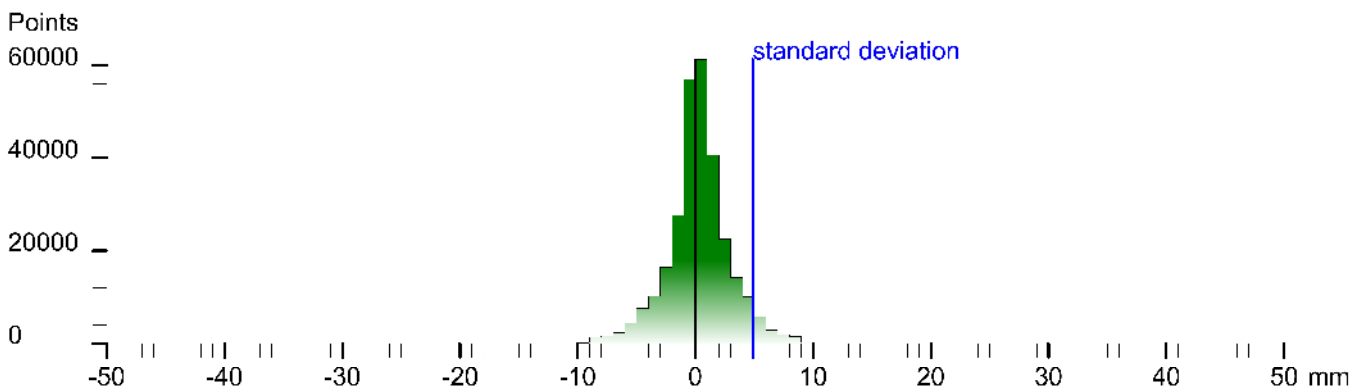
Status registration '[102h] registered with cloud to cloud'

Registration matrix:

```
0.443508 -0.896271 -0.000235 -10.0361 m
0.896271 0.443506 -0.000251 -4.8567 m
0.000328 -0.000101 1.000000 0.9658 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:4.9 mm

Deviation histogram



Scan '75'

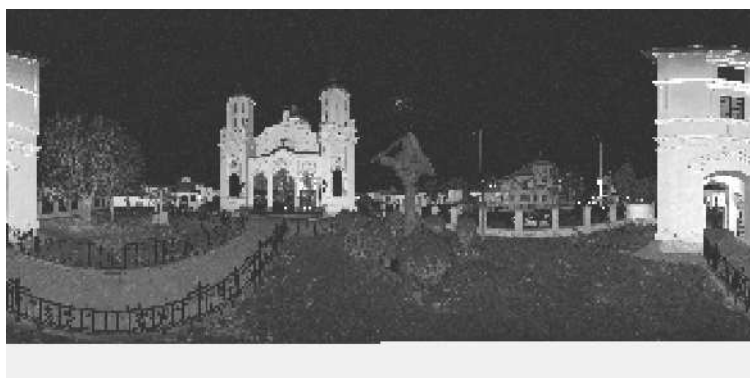
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan position: [102h] registered with cloud to cloud
Sensor
sensors: 3100 * barometer transition rotation gps
Barometer: 1.001350 bar 93.5453 m
nav translation: -3.7188 m 10.1699 m 98.1618 m accuracies: 10.2586 m 10.2586 m 0.0001 m
nav rotation: 0.0000 0.0000 294.8919 accuracies: 0.0000 0.0000 15.0000
upside-down: no
GPS lat:44.943352 long:26.029011 satellites:4 height:162.1 m hdop:3.0 vdoop:4.0 m hacc:10.0 m vacc:11.0 flags:G3 'stand alone 3D solution'
north:1977116.077 m east:423395.811 m zone:35T
Initial pre position (3-coo, tocoo):
0.413 -0.911 0.000 -22.636
0.911 0.413 0.000 -37.277
0.000 0.000 1.000 -52.550
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



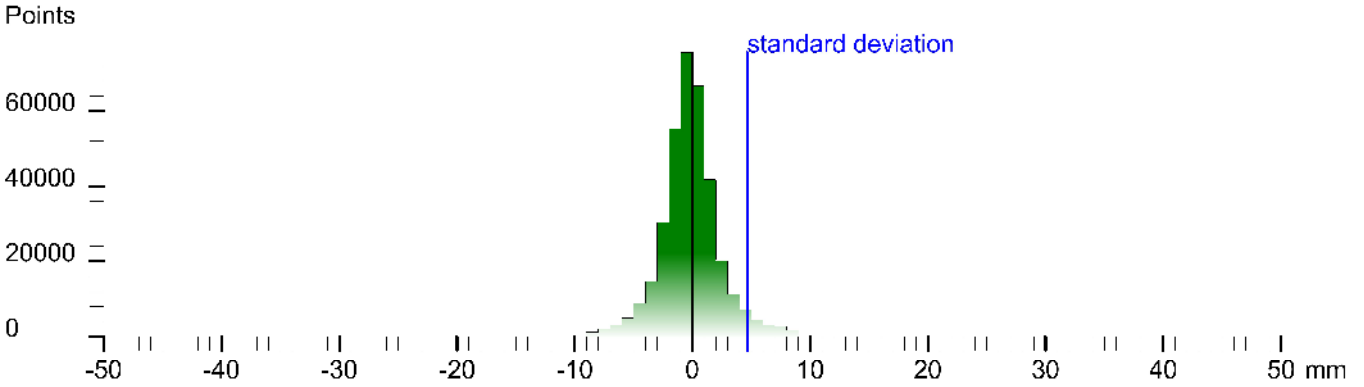
Scan position '76'

Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```
-0.003447  0.999994  -0.000286  -11.8493 m
-0.999994  -0.003447  0.000184  -0.0291 m
0.000184  0.000287  1.000000  0.2259 m
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation:4.7 mm

Deviation histogram



Scan '76'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: full LPS scan of 303 models: 148:757 scan: 76 type: Bv 876 e7 scan: Bv 876 e7 spot: 3616 *compared to the file: 3616 e7 source: Point *no comment see file: 3616 e7 scan: 76 *148: 181 * for 1 2074 e7 1940
Sensor
sensors: 3100 *barome or transition rotation gps
Barometer: 1.001414 bar 93.0023 m
nav translation: 2.7705 m 20.3982 m 98.1139 m accuracies: 15.5591 m 15.5591 m 0.0000 m
nav rotation: 0.0000 0.0000 62.0607 accuracies: 0.0000 0.0000 15.0000
upside-down: no
GPS lat:44.943375 long:26.028955 satellites:5 height:185.6m hdop:2.7 vdcp:3.6m hacc:25.0m vacc:4.6 flags:G3 's are alone 3D solution'
north:1977116.672 m east:423391.178 m zone:35T
Initial pre position (3-coor):
0.38 0.990 0.000 -9.861
-0.990 0.138 0.000 -17.173
0.000 0.000 1.000 -53.298
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '77'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

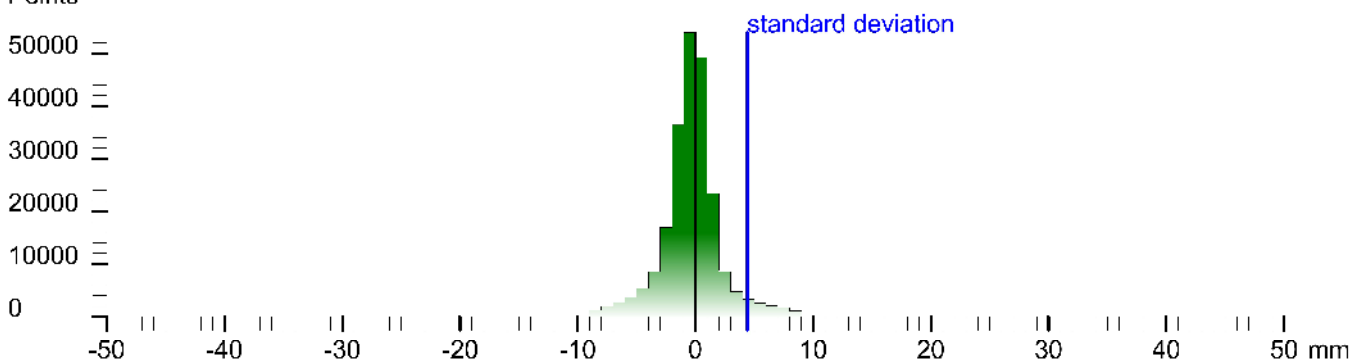
Registration matrix:

-0.714233	0.699908	-0.000481	-17.8297 m
-0.699908	-0.714233	-0.000251	2.9619 m
-0.000520	0.000158	1.000000	0.2464 m
0.000000	0.000000	0.000000	1.0000

Result registration cloud to cloud standard deviation:4.4 mm

Deviation histogram

Points



Scan '77'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Scan comment: '14:03:11 14:03:11 14:03:11 77' serial: '5016-0100' firmware: '9.0.3.6562-0' quality: 'Normal' resolution: 'High' sensor: 'Z+F IMAGER 5016'
Sensor
sensors: 3100 *barometric transition rotation gps
Barometer: 1.001384 bar 93.2518 m
nav translation: -1.2136 m -3.5125 m 98.7892 m accuracies: 6.9877 m 5.9877 m 3.0000 m
nav rotation 0.0000 0.0000 0.0000 *50.7677 accuracies: 0.0000 0.0000 1s.0000
upside-down: no
GPS lat:44.943119 long:26.629131 satellites:3 height:105.3 m hdpof:5.1 vdpof:1.0 m hacc:17.4 m vacc:19.0 fsgs:G2 *stand alone 2D solution*
north:1977390.114 nr east:42310.88 m zone:35T
Initial pre position (0:indoor)
-0.653 0 757 0.000 -71.105
-0.757 0.855 0.000 -20.886
0.000 0.000 1.000 -52.923
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '78'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

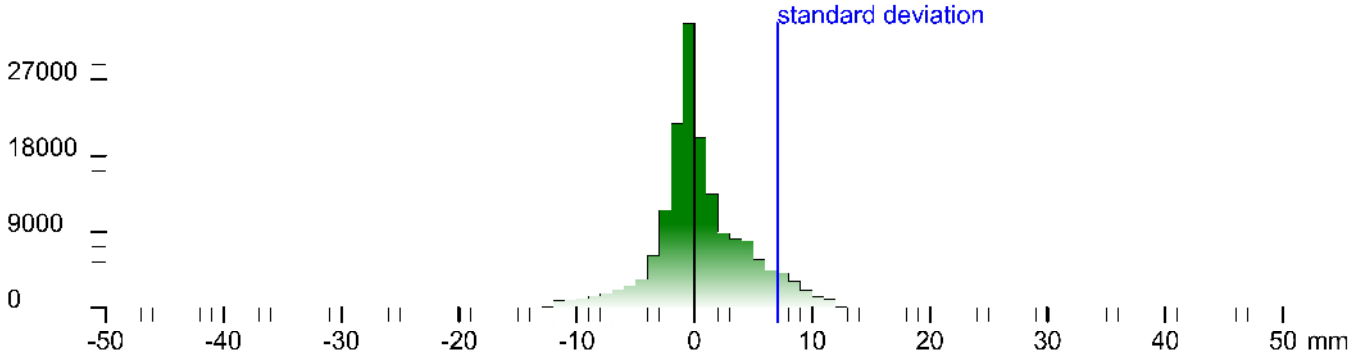
Registration matrix:

```
-0.422380  0.906419  -0.000073  -9.4701 m  
-0.906419  -0.422380  -0.000199  12.9592 m  
-0.000212  -0.000017  1.000000   0.2795 m  
0.000000   0.000000   0.000000   1.0000
```

Result registration cloud to cloud standard deviation:7.0 mm

Deviation histogram

Points



Scan '78'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata Value comment operator

```
Scan comment: full 19080x1031 mm scale: 1.48:78' scan no: 78' scan: 'Bw, 816' m' speed: 0.444' compensation: none' sensor: '27' source: 'Point' scan comment: 'see file: 'cloud to cloud' for '12'4' 181' for '12'4' and '194'  
Sensor  
sensors: 3100 * barome or transition rotation gps  
Barometer: 1.001390 bar 93.2057 m  
nav translation: 7.2300 m 7.281' m 98.73' 5 m accuracies: 10.2551 m 10.2551 m 0.0000 m  
nav rotation: 0.0000 0.0000 0.067732 accuracies: 0.0000 0.0000 15.0000  
upside-down: no  
GPS lat: 44.943569 long: 26.029196 satellites: 3 height: 102.6m hdop: 4.9 vdcpr: 1.0m hacc: 7.0m vacc: 13.0 tags: G2 'stand alone 2D solution'  
north: 1977110.057 m east: 4234' 0.696 m zone: 35T  
Initial pre position (3-coor):  
-0.789 0.957 0.000 -13.875  
-0.957 -0.289 0.000 -13.405  
0.000 0.000 1.000 -52.980  
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '79'

Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

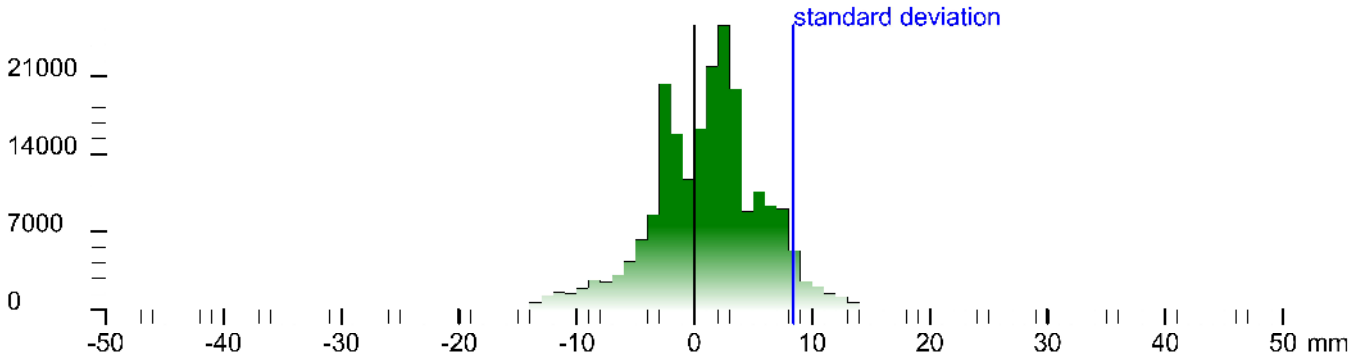
```

0.622690 -0.782469 -0.000362 -10.9379 m
0.782469 0.622689 0.000262 16.6492 m
0.000020 -0.000447 1.000000 0.4286 m
0.000000 0.000000 0.000000 1.0000
    
```

Result registration cloud to cloud standard deviation:8.4 mm

Deviation histogram

Points



Scan '79'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```

Scan comment: '148:79'
Sensor
sensors: 3100 *barometric transition rotation gps
Barometer: 1.001336 bar 93.6556 m
nav translation: -1.2767 m 3.6079 m 99.1206 m accuracies: 5.8366 m 5.8366 m 0.0001 m
nav rotation: 0.0000 0.0000 0.0000 accuracies: 0.0000 0.0000 1s.0000
upside-down: no
GPS lat:44.9435+2 long:26.029072 satellites:4 height:101.6m hdoop:4.9 vdoop:5.9m hacc:17.0m vacc:13.0 flags:GS 'stand alone 3D solution'
north:1977137.207 m east:423400.880 m zone:35T
Initial pre position (3-coor):
0.603 -0.798 0.000 -15.151
0.798 0.803 0.000 -2.801
0.000 0.000 1.000 -52.591
0.000 0.000 0.000 1.000
    
```

Level system info: dynamic compensator available.



Scan position '8'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

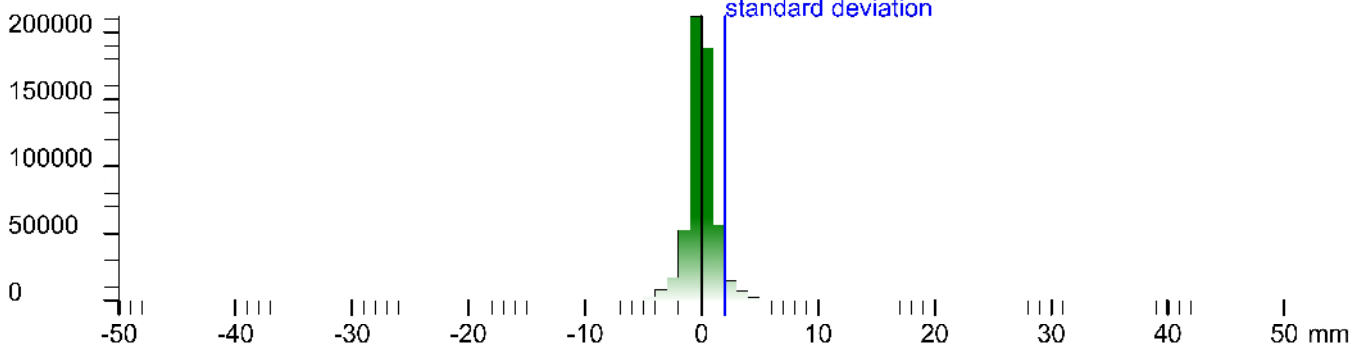
Registration matrix:

```
0.999014  0.044405  -0.000127  14.2876 m
-0.044405  0.999015  -0.000002  0.8092 m
0.000128  0.000007  1.000000  0.6907 m
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation:2.0 mm

Deviation histogram

Points



Scan '8'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: '14082016 10:31' filename: '14082016 10:31' sensor: 'Z+F IMAGER 5016' file: '14082016 10:31' position: '14082016 10:31' registration: '14082016 10:31' scan resolution: 'High' scan quality: 'Normal' scan date: '2016-08-21 10:31' scan time: '2016-08-21 10:31'
Sensor
sensors: 3096 *barometric transition rotation*
Barometer: 0.991908 bar *79.202 m
nav translation: -3.2892 m -3.1240 m 173.7773 m accuracies: 0.0908 m 0.6908 m 0.0000 m
nav rotation: 0.0000 0.0000 *5520 accuracies: 0.0000 0.0000 /5.4062
upside-down: no
Initial pre position: (Girdoor)
1.000 0.027 0.000 -5.623
-3.027 1.000 0.000 -4.721
0.000 0.000 1.000 -2.000
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '80'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

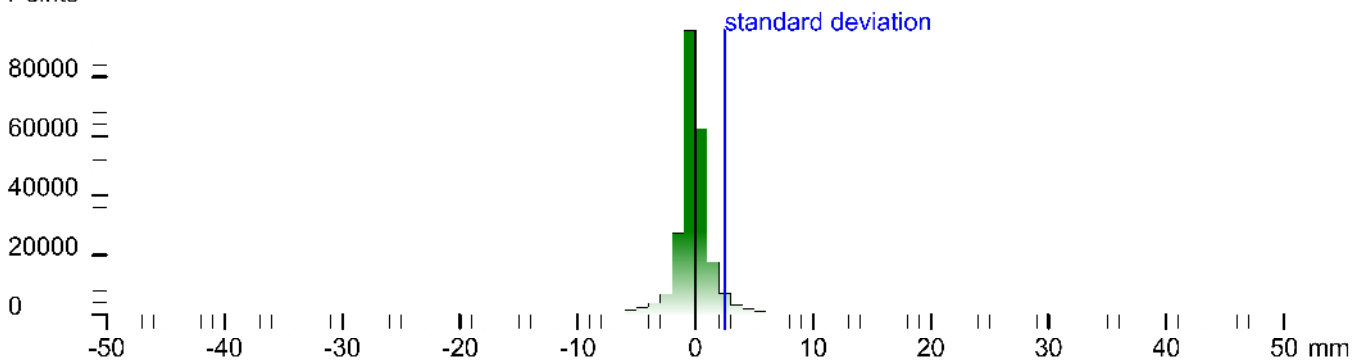
Registration matrix:

0.889957	0.456045	-0.000215	-25.4170 m
-0.456044	0.889956	0.000799	44.0853 m
0.000556	-0.000613	1.000000	0.1744 m
0.000000	0.000000	0.000000	1.0000

Result registration cloud to cloud standard deviation:2.5 mm

Deviation histogram

Points



Scan '80'

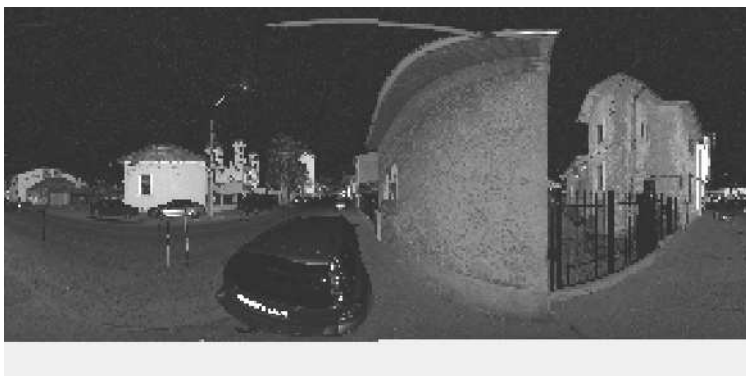
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: full 100% scan of building facade  
Sensor  
sensors: 3100 *barome or transition rotation gps  
Barometer: 1.001342 bar 93.6065 m  
nav translation: 8.135 m 26.3448 m 89.0840 m accuracies: 19.2026 m 19.2026 m 0.0000 m  
nav rotation: 0.0000 0.0000 26.7699 accuracies: 0.0000 0.0000 19.0000  
upside-down: no  
GPS lat:44.943752 long:26.026960 satellites:4 height:189.9m hdop:2.6 vldop:4.9m hacc:7.8-m vacc:12.0 flags:G3 's:unc stable 3D solution'  
north:1977160.611 m east:423393.033 m zone:35T  
Initial pre position (3-coor):  
0.693 0.450 0.000 -7.038  
-0.450 0.693 0.000 -3.544  
0.000 0.000 1.000 -82.627  
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '82'

Scan position is member of group(s):

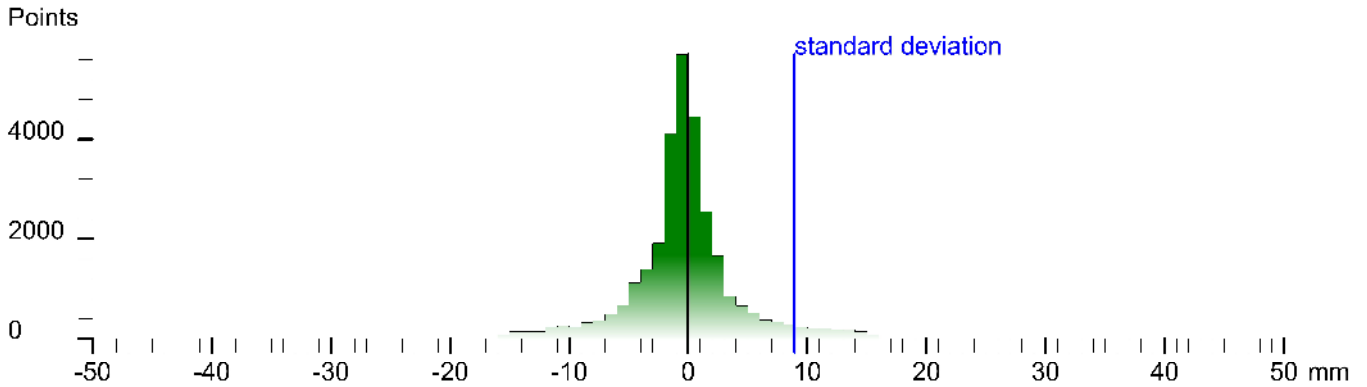
Status registration '[102h] registered with cloud to cloud'

Registration matrix:

```
-0.189775  0.981828  -0.000055  -27.4567 m
-0.981828  -0.189774  0.000489  37.7372 m
0.000472  0.000148  1.000000   0.1801 m
0.000000  0.000000  0.000000   1.0000
```

Result registration cloud to cloud standard deviation: 8.9 mm

Deviation histogram



Scan '82'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan: 2025-11-14 19:38:42.311 mtime: 146752 scanid: 82 type: Bv 816 e17 name: Bv 816 e17 position: data:compensator = no; sensor = 27; source: Point; scan: normal; scan: registered; scan: add: full = 1; * 4; 181 = for 1; 20; 4; 194
Sensor
sensors: 3100 * barome or transition rotation gps
Barometer: 1.001381 bar 93.2778 m
nav translation: -1.7535 m -7.139° m 98.16° 9 m accuracies: 8.8159 m 8.8159 m 0.0000 m
nav rotation: 0.0000 0.0000 69.886° 6 accuracies: 0.0000 0.0000 1s 0.0000
upside-down: no
GPS lat: 44.943687 long: 26.028940 satellites: 5 height: 106.0m hhdop: 2.2 vdop: 3.0m hacc: 9.4-m vacc: 14.0 flags: G3 's: s: s: s: s: s: 3D solution'
north: 197.7163 / 35 m east: 423389.690 m zone: 35T
Initial pre position (3-coor):
0.000 1.000 0.000 -21.370
-1.000 0.002 0.000 -13.623
0.000 0.000 1.000 -52.550
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '83'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

Registration matrix:

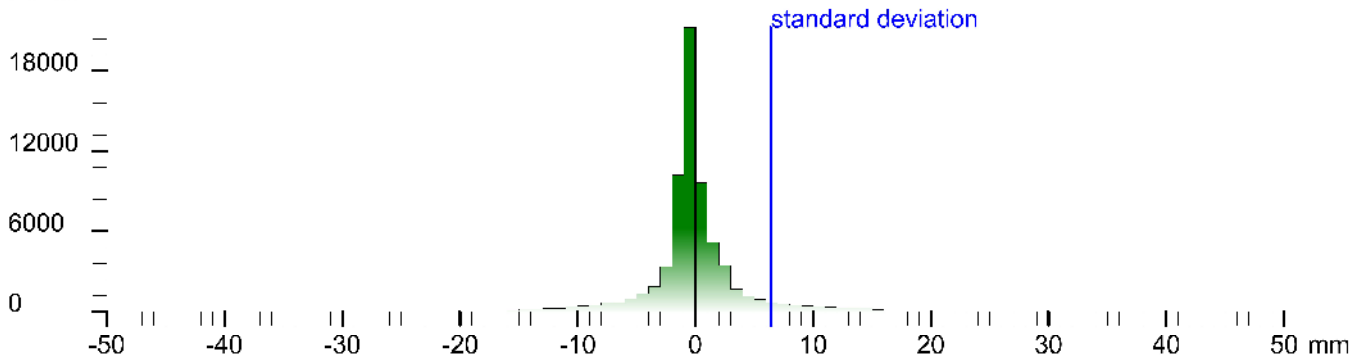
```

0.187849  0.982198  -0.000533  -31.2911 m
-0.982198  0.187849  -0.000219   8.8240 m
-0.000115  0.000565   1.000000   0.0487 m
0.000000  0.000000   0.000000   1.0000
    
```

Result registration cloud to cloud standard deviation:6.4 mm

Deviation histogram

Points



Scan '83'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```

Scan position: lat:19.984403 lon:14.161594 alt:85.797 m * coord: Bv:8.76 m * speed: 0.00 m/s * compass: 0 m/s * sensor: 27 * source: Point * scan position: 19.984403 lon: 14.161594 alt: 85.797 m
Sensor
sensors: 3100 * barome or transition rotation gps
Barometer: 1.001384 bar 93.2518 m
nav translation: -1.9974 m -30.3385 m 98.5096 m accuracies: 20.7060 m 20.7060 m 0.0000 m
nav rotation: 0.0000 0.0000 0.1463 accuracies: 0.0000 0.0000 15.0000
upside-down: no
GPS lat:44.943401 lon:26.028872 satellites:3 height:183.4m hhdop: 3.5 vdop: 1.0m hacc:0.4m vacc:22.0 tags:G2 *stand alone 2D solution
Initial pre position (3-coor):
0.273 0.982 0.000 -26.367
-0.982 0.273 0.000 -44.162
0.000 0.000 1.000 -53.202
0.000 0.000 0.000 1.000
    
```

Level system info: dynamic compensator available.



Scan position '84'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

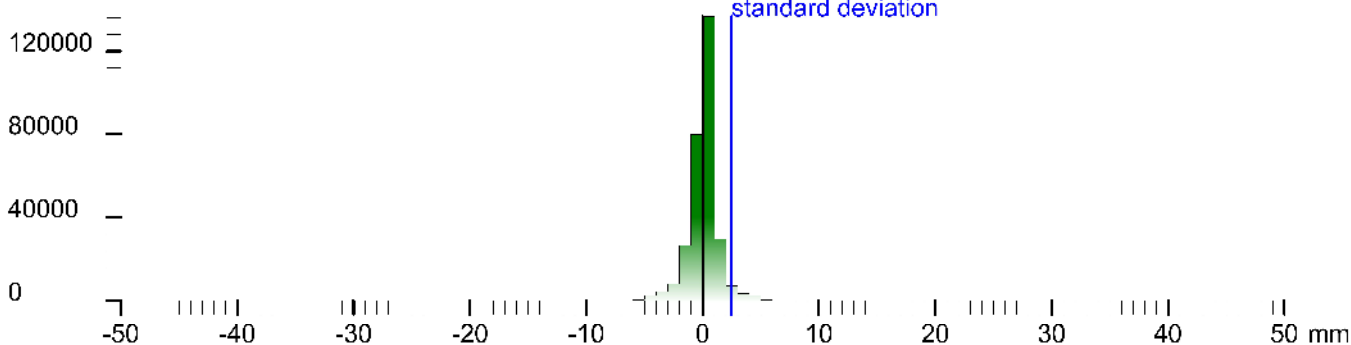
Registration matrix:

0.509229	0.860631	-0.000082	-22.8662 m
-0.860631	0.509229	-0.000068	-2.7815 m
-0.000016	0.000105	1.000000	-0.0537 m
0.000000	0.000000	0.000000	1.0000

Result registration cloud to cloud standard deviation:2.5 mm

Deviation histogram

Points



Scan '84'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

Sensor

sensors: 3100 *barome or transtion rotation gps
Barometer: 1.001366 bar 93.403 m
nav translation: 7.5696 m -6.0085 m 99.1177 m accuracies: 9.9676 m 9.9676 m 0.0000 m
nav rotation: 0.0000 0.0000 0.0000 accuracies: 0.0000 0.0000 1s.0000
upside-down: no
GPS lat:14.943256 long:26.029024 satellites:3 height:182.0m hdop:4.5 vdcop:1.0m hacc: 3.0m vacc:14.0 tags:G2 *stand alone 2D solution
north:1977105.70 m east:423386.737 m zone:35T
Initial pre position (3.o. t.coor):
0.607 0.795 0.000 - 8.801
-0.795 0.807 0.000 -50.17C
0.000 0.000 1.000 -52.567
0.000 0.000 0.000 1.000

Level system info: dynamic compensator available.



Scan position '85'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

Registration matrix:

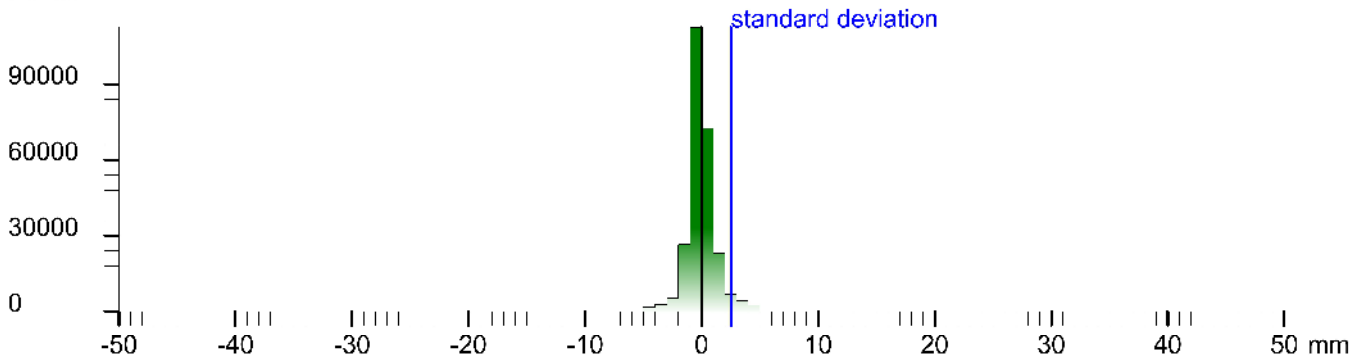
```

0.990331  0.138725  -0.000494 -33.0287 m
-0.138724 0.990331  0.000503  0.1351 m
0.000560 -0.000431  1.000000  0.0478 m
0.000000  0.000000  0.000000  1.0000
    
```

Result registration cloud to cloud standard deviation: 2.5 mm

Deviation histogram

Points



Scan '85'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata Value comment operator

```

Sensor
sensors: 3100 *barome or transition rotation gps
Barometer: 1.001202 bar * 00.025 m
nav translation: -1.6184 m -2.9175 m 99.1155 m accuracies: 6.8106 m 6.8106 m 0.0000 m
nav rotation: 0.0000 0.0000 5.3663 accuracies: 0.0000 0.0000 1/8 rad665
upside-down: no
GPS lat:44.943395 long:26.028921 satellites:4 height:206.2m hdop:5.1 vdcpr:0.1m hacc:7.0m vacc:4.4 flags:G3's are using 3D solution'
north:197.7121,247 m east:423388.798 m zone:35T
Initial pre position (300, toor):
0.998 0.059 0.000 -20.421
-0.059 0.998 0.000 -53.008
0.000 0.000 1.000 -52.296
0.000 0.000 0.000 1.000
    
```

Level system info: dynamic compensator available.



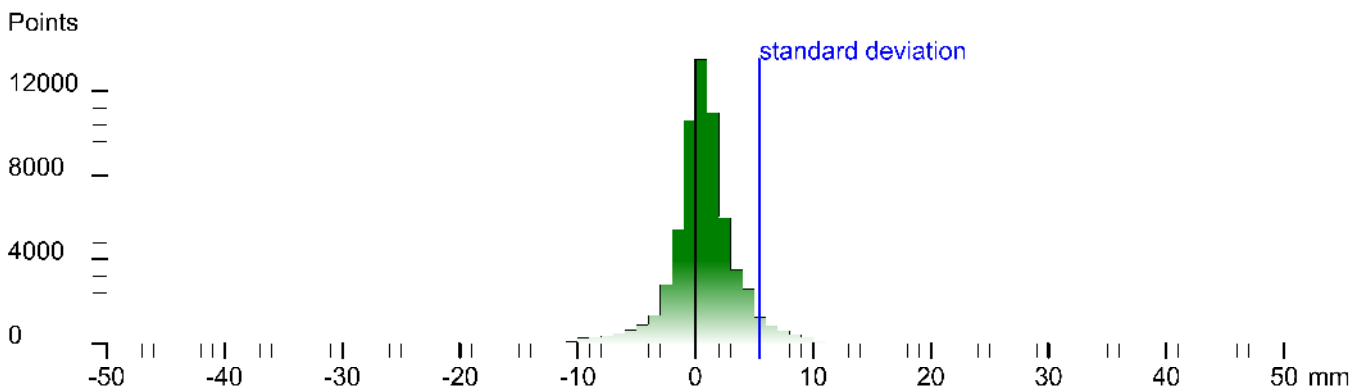
Scan position '86'

Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```
0.043617 -0.999049 -0.000474 -40.5040 m
0.999048 0.043617 0.000065 -16.9753 m
-0.000045 -0.000477 1.000000 -0.1208 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:5.4 mm

Deviation histogram



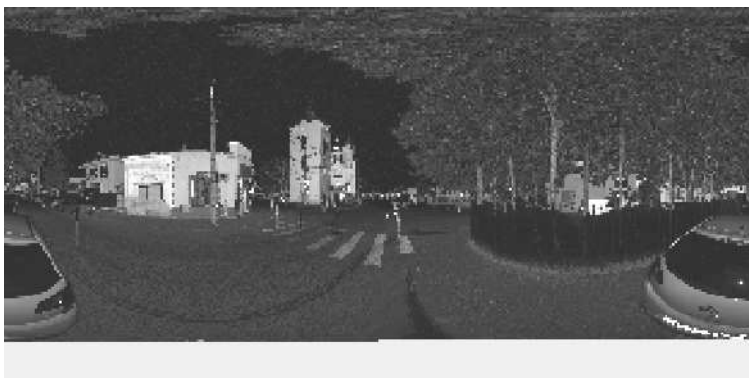
Scan '86'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: full 1.908sec 3.03 m radius 1.48:189 m radius 96°qph 8.7°V of 1° radius 8.7°V of 1°qph: for data "compensator" in use: set at 27 hours "Point" for a common use for: resolution="12.46:181" for 1.20°x4.1794"
Sensor
sensors: 3100 *barome or transition rotation gps
Barometer: 1.001247 bar *00.407 m
nav translation: 4.7532 m -10.0127 m 99.5094 m accuracies: 10.9066 m 10.9660 m 0.0001 m
nav rotation: 0.0000 0.0000 2/3.230 / accuracies: 0.0000 0.0000 1s.0000
upside-down: no
GPS lat:44.943256 long:26.028725 satellites:6 height:195.2m hddos: 7 vdcop:2.4m hacc: 8.0m vacc:5.5 flags:G3 's are alone 3D solution'
north:1977105.753 m east:423373.113 m zone:35T
Initial pre position (3.o. tocoor)
0.057 -0.998 0.000 -44.840
0.990 0.057 0.000 -47.150
0.000 0.000 1.000 -52.202
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '87'

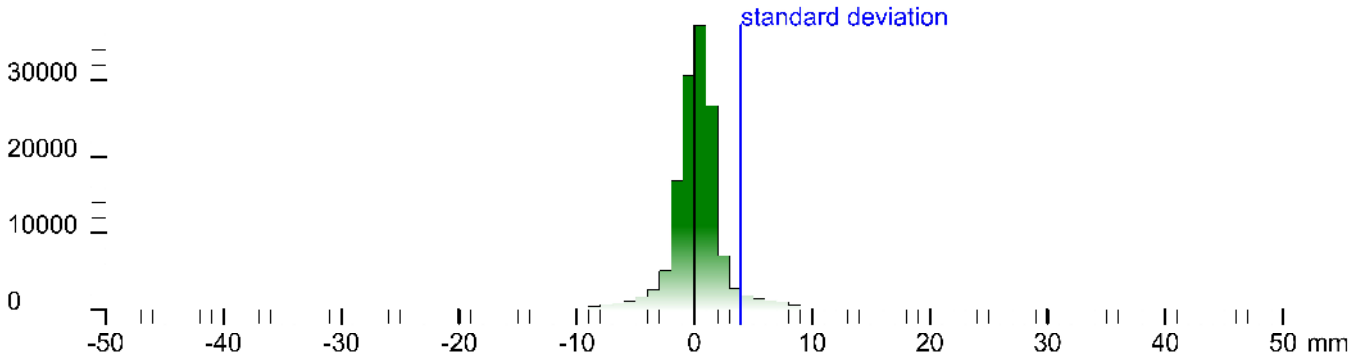
Scan position is member of group(s):
Status registration '[102h] registered with cloud to cloud'
Registration matrix:

0.254126	-0.967173	-0.000580	-54.3392 m
0.967171	0.254127	-0.000043	-15.8225 m
0.000187	-0.000551	1.000000	0.0743 m
0.000000	0.000000	0.000000	1.0000

Result registration cloud to cloud standard deviation:3.9 mm

Deviation histogram

Points



Scan '87'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
Scan resolution 'High' quality 'Normal'

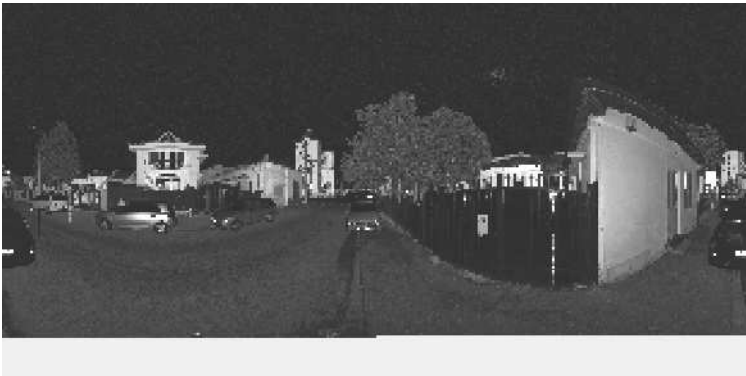
Metadata **Value**
comment
operator

Scan command: call LPS@user:3031 filename:148:187 filename:87.qsh/Btu.87.0100.qsh/points/876/compensation/compensation/27/scan/Point/scan/compensation/compensation/148:187/for/1/2074617940

Sensor

sensors: 3100 *barome or transition rotation gps
Barometer: 1.001093 bar / 01.702 m
nav translation: -10.4840 m 1.0846 m 100.4799 m accuracies: 10.3983 m 10.3983 m 0.0001 m
nav rotation: 0.0000 0.0000 280.4e63 accuracies: 0.0000 0.0000 1s.0000
upside-down: no
GPS lat:44.943237 long:26.028581 satellites:6 height:102.7m hddos:0.8 vdcop:2.3m hacc:0.0m vaco:6.8 flags:G3 's are alone 3D solution'
north:1977103.789 m east:423363.146 m zone:35T
Initial pre position (3-coor):
0.81 -0.983 0.000 -57.804
0.963 0.101 0.000 -49.115
0.000 0.000 1.000 -51.282
0.000 0.000 0.000 1.000

Level system info: dynamic compensator available.



Scan position '88'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

Registration matrix:

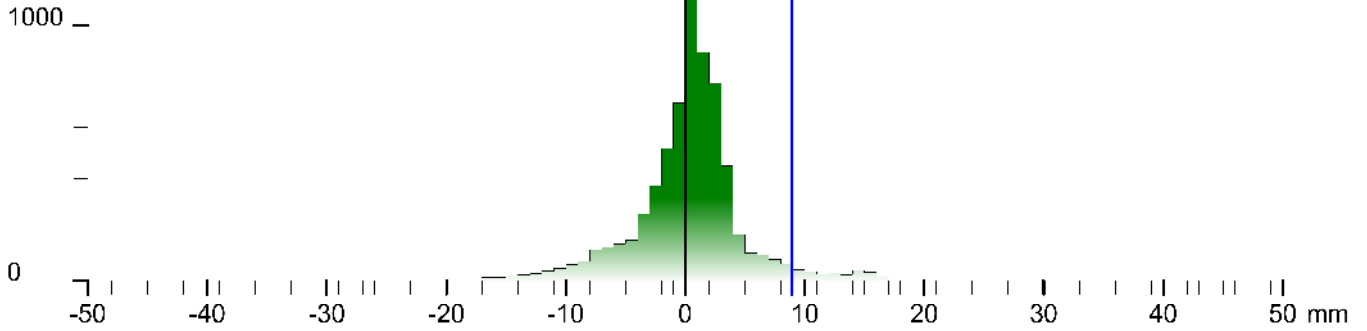
```

0.110824  0.993841  -0.000563  -64.1638 m
-0.993840  0.110824  -0.000513  -16.0958 m
-0.000446  0.000617  1.000000   0.1435 m
0.000000  0.000000  0.000000   1.0000
    
```

Result registration cloud to cloud standard deviation:9.0 mm

Deviation histogram

Points



Scan '88'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

Sensor

```

sensors: 3100 * barometer transition rotation gps
Barometer: 1.001037 bar * 02.174 m
nav translation: -3.8692 m -2.8968 m 10 * .2471 m accuracies: 10.2877 m 10.2877 m 0.0000 m
nav rotation: 0.0000 0.0000 /5.0689 accuracies: 0.0000 0.0000 /5.0000
upside-down: no
GPS: lat:44.9432+1 long:26.028437 satellites:6 height:102.0m hdxcc:2.0 vdxcc:2.2m hacc:6.0-m vacc:8.6 flags:G3 'stand alone 3D solution'
north:4977104.330 m east:423350.370 m zero:35T
Initial pre position (3-coo, tocoor):
0.241 0.971 0.000 -67.473
-0.971 0.241 0.000 -51.952
0.000 0.000 1.000 -53.165
0.000 0.000 0.000 1.000
    
```

Level system info: dynamic compensator available.



Scan position '89'

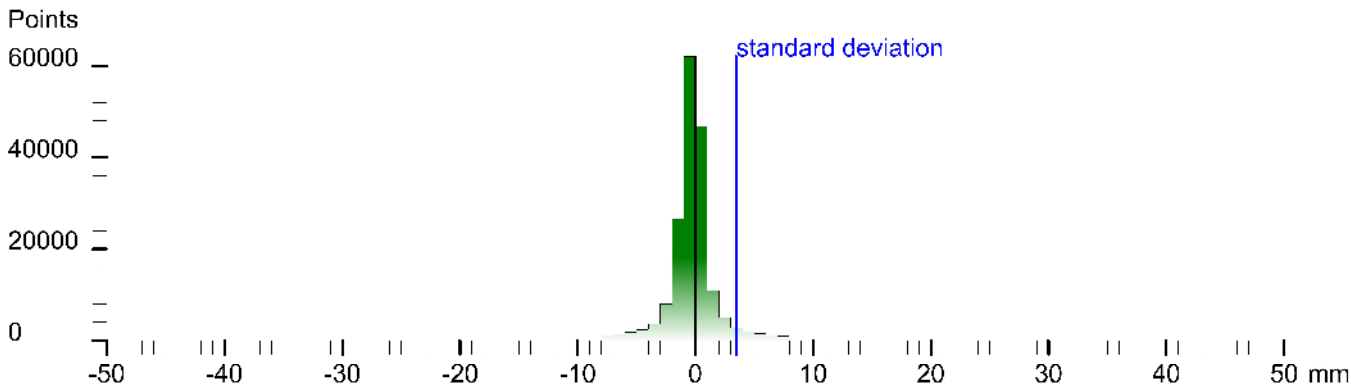
Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```

0.989770  0.142677  -0.000694  -65.0514 m
-0.142676  0.989770  -0.000159  -8.3740 m
0.000666  0.000255  1.000000  0.1220 m
0.000000  0.000000  0.000000  1.0000
    
```

Result registration cloud to cloud standard deviation:3.5 mm

Deviation histogram



Scan '89'

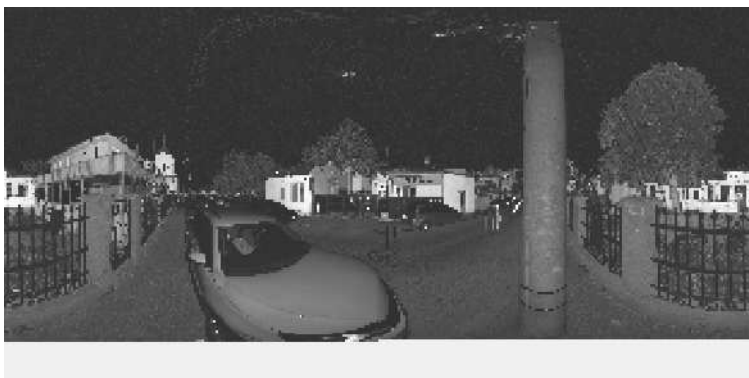
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```

Sensor
sensors: 3100 *barome or transition rotation gps
Barometer: 1.000092 bar / 02.55 m
nav translation: 0.9597 m 6.7618 m 102.3387 m accuracies: 8.5615 m 8.5615 m 3.0000 m
nav rotation: 0.0000 0.0000 36.8863 / accuracies: 0.0000 0.0000 161. / 1s
upside-down: no
GPS lat:44.943279 long:26.028423 satellites:5 height:186.8m hhdop:1.7 vhdop:2.8m hacc:5.0-m vacc:8.2 flags:G3 'stand alone 3D solution'
north:1977108.581 m east:423349.368 m zone:35T
Initial pre position (3-coo. tocor):
0.999 -0.055 0.000 -68.435
0.055 0.999 0.000 -44.310
0.000 0.000 1.000 -79.373
0.000 0.000 0.000 1.000
    
```

Level system info: dynamic compensator available.



Scan position '9'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

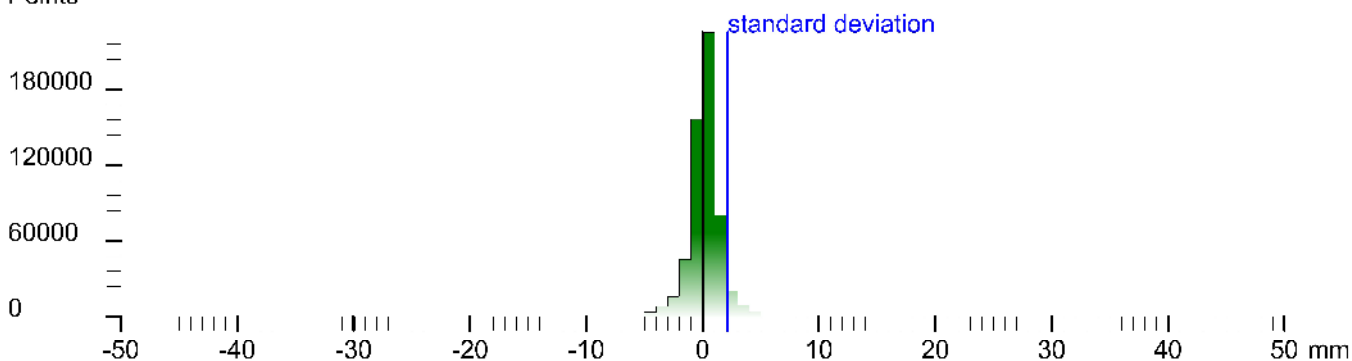
Registration matrix:

```
0.982538 -0.186065 -0.000126 13.4353 m
0.186065 0.982538 0.000175 5.2337 m
0.000093 -0.000196 1.000000 0.6967 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 2.2 mm

Deviation histogram

Points



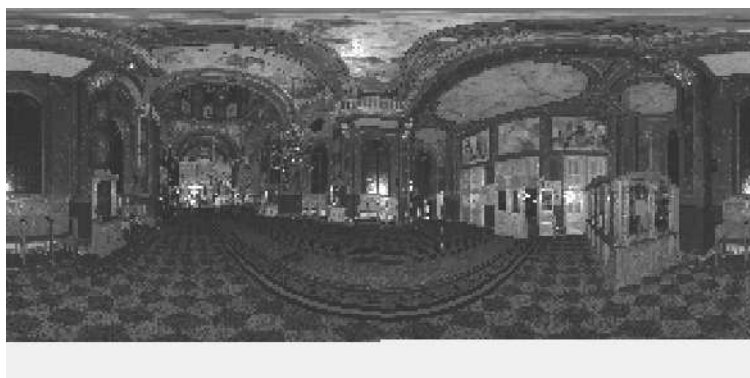
Scan '9'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Scan command: 'cat /proc/bus/usb/lsp | grep -m 1 -E "vendor=0x00000000|product=0x00000000" | cut -d= -f 2 | sed -e "s/ / /g" | sed -e "s/\"/>Level system info: dynamic compensator available.
```



Scan position '90'

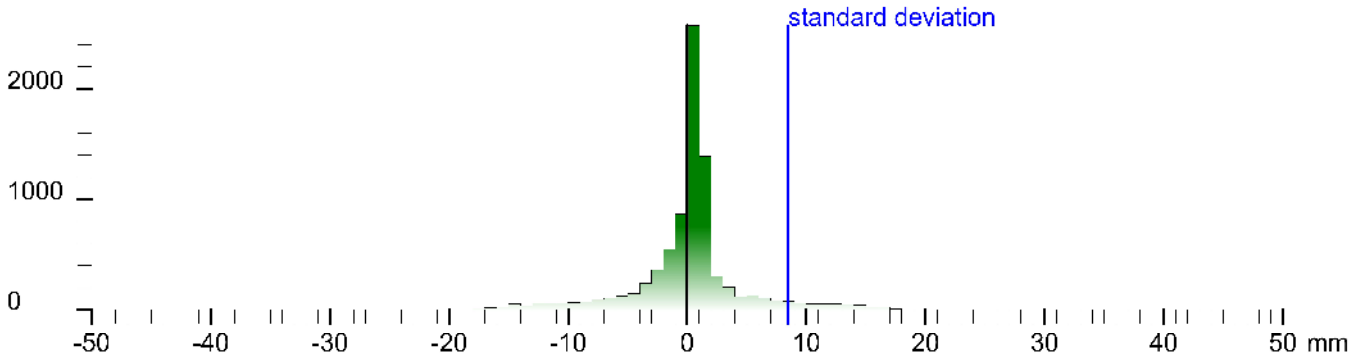
Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```
0.949946  0.312421  -0.000502  -59.5417 m
-0.312419  0.949945  0.000000  -9.0006 m
0.000477  0.000156  1.000000  -0.0021 m
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation:8.5 mm

Deviation histogram

Points



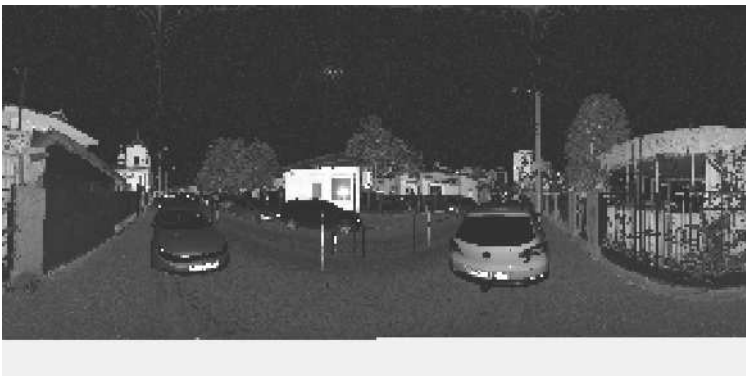
Scan '90'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: full 1.928sec 303° manual 1.4h:107 manual 90° auto 'Bw 8' 6' 0' speed: 3040 'compensator' in use: sensor 22' source: 'Point' for common use for: resolution: 0.074mm/pt for 120° and 180° for 120° and 180°
Sensor
sensors: 3100 *barometric transition rotation gps
Barometer: 1.000043 bar * 02.067 m
nav translation: 3.0116 m 0.9874 m 102.1670 m accuracies: 0.6877 m 0.6877 m 0.0000 m
nav rotation: 0.0000 0.0000 * 3.313 / accuracies: 0.0000 0.0000 1s.0000
upside-down: no
GPS lat: 44.943302 long: 26.026470 satellites: 5 height: 101.4m hddop: .8 vddop: 2.7m hacc: 5.8-m vacc: 8.0 flags: G3 'stand alone 3D solution'
Initial pre position (3-coor):
0.973 0.230 0.000 -63.986
-0.230 0.973 0.000 -41.817
0.000 0.000 1.000 -79.545
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '91'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

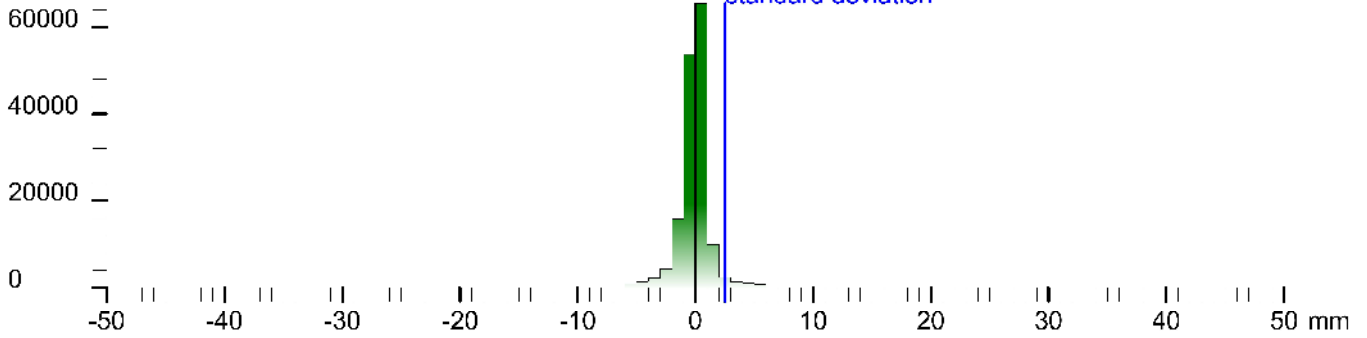
Registration matrix:

```
0.872306 -0.488963 -0.000441 -36.1270 m
0.488962 0.872306 -0.000384 -24.0191 m
0.000573 0.000119 1.000000 -0.1657 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:2.5 mm

Deviation histogram

Points



Scan '91'

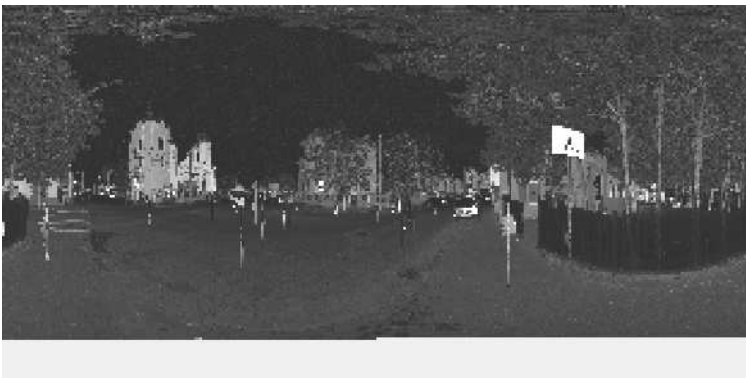
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

Sensor: 3100 *barometric transition rotation gps
Barometer: 1.000016 bar *03.189 m
nav translation: 14.7108 m *22.1006 m *102.8382 m accuracies: 18.6410 m 18.5110 m 0.0001 m
nav rotation: 0.0000 0.0000 0.0000 0.0000 accuracies: 0.0000 0.0000 1s.0000
upside-down: no
GPS lat:44.943172 lon:26.028744 satellites:3 height:188.2m hdop:4.2 vdcpr:1.0m hacc:5.0m vacc:6.8 flags:G2's error alarm 2D solution'
north:1977986/13 m east:423371.506 m zone:35T
Initial pre position (3coo_tcoor):
0.857 -0.498 0.000 -49.246
0.490 0.887 0.000 -83.917
0.000 0.000 1.000 -78.877
0.000 0.000 0.000 1.000

Level system info: dynamic compensator available.



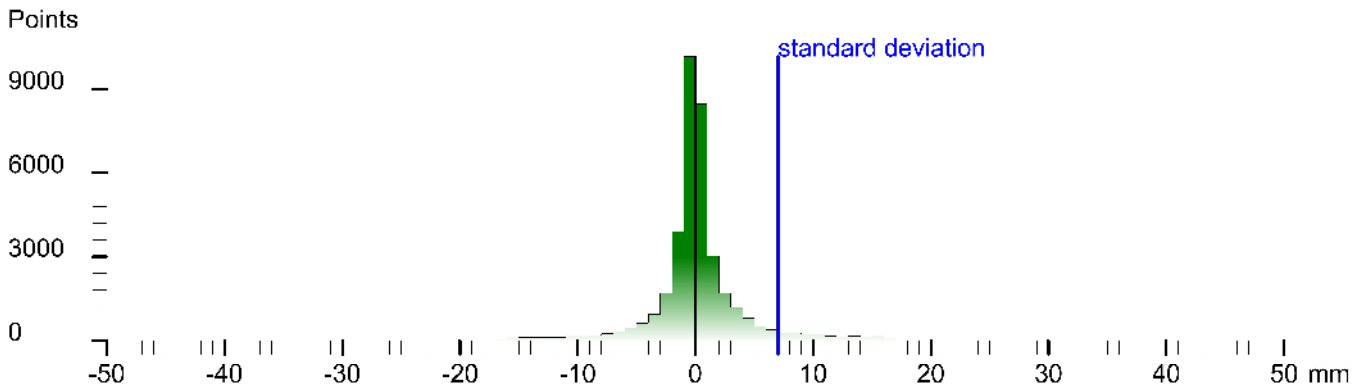
Scan position '92'

Scan position is member of group(s):
Status registration '[102h] registered with cloud to cloud'
Registration matrix:

```
0.590101 -0.807331 -0.000477 -42.0417 m  
0.807330 0.590101 -0.000479 -39.9165 m  
0.000669 -0.000104 1.000000 -0.1736 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 7.0 mm

Deviation histogram



Scan '92'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Scan command: cat /dev/ttyUSB0 303 -> /dev/ttyUSB0  
Sensor  
sensors: 3100 *barometer/transition/rotation/gps  
Barometer: 1.000898 bar / 03.342 m  
nav/translation: 7.7009 m / -11.8316 m / 102.7987 m accuracies: 12.253 / m 12.2534 m 0.0000 m  
nav/rotation: 0.0000 0.0000 0.0000 532.6169 accuracies: 0.0000 0.0000 1s, 0.0000  
upside-down: no  
GPS lat: 44.943020 long: 26.028687 satellites: 5 height: 194.7m hddos: 2.7 vdcpl: 0.4m hacc: 8.0m vacc: 11.0 lls: G3 'stand alone 3D solution'  
north: 197.7078, 516 m east: 423369.788 m zone: 35T  
Initial pre position (3-coo. tocoor):  
0.539 -0.822 0.000 -41.545  
0.842 0.538 0.000 -75.848  
0.000 0.000 1.000 -78.913  
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '93'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

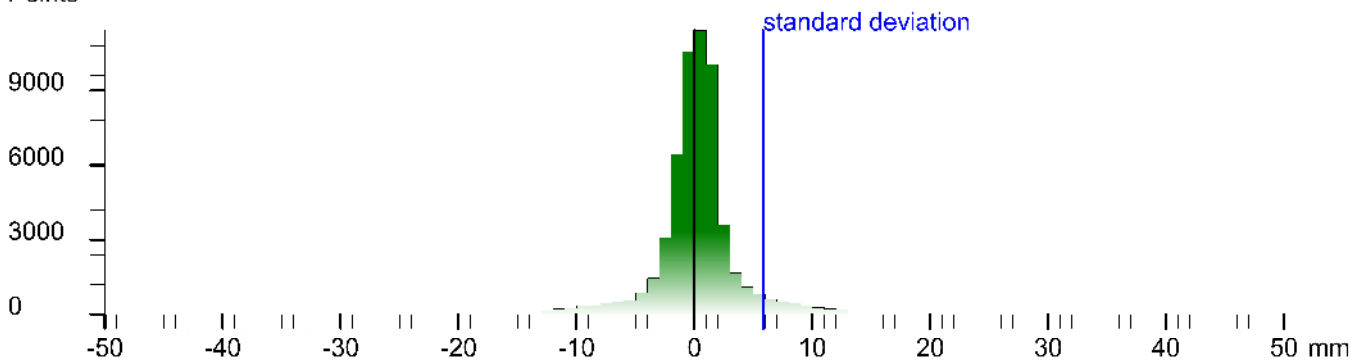
Registration matrix:

```
0.576916 -0.816805 -0.000539 -46.7847 m
0.816804 0.576916 -0.000608 -48.1355 m
0.000808 -0.000091 1.000000 -0.1412 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:5.8 mm

Deviation histogram

Points



Scan '93'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: null
Sensor
sensors: 3100 *barome or transition rotation gps
Barometer: 1.000760 bar / 34.50" m
nav translation: 2.0757 m -3.9809 m 103.7671 m accuracies: 7.3603 m 7.3603 m 0.0000 m
nav rotation: 0.0000 0.0000 0.0000 0.0000 0.0000 0.0000 accuracies: 0.0000 0.0000 1s:0.0000
upside-down: no
GPS lat:44.942096 long:26.026684 satellites:5 height:186.3m hdxo:2.1 vdcop:2.5m hacc:8.4-m vacc:10.0 flags:G3 's same same 3D solution'
north:1977370.215 m east:423367.871 m zone:35T
Initial pre position (3-coo. tocoor):
0.655 -0.501 0.000 -39.469
0.501 0.665 0.000 -79.836
0.000 0.000 1.000 -77.945
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '95'

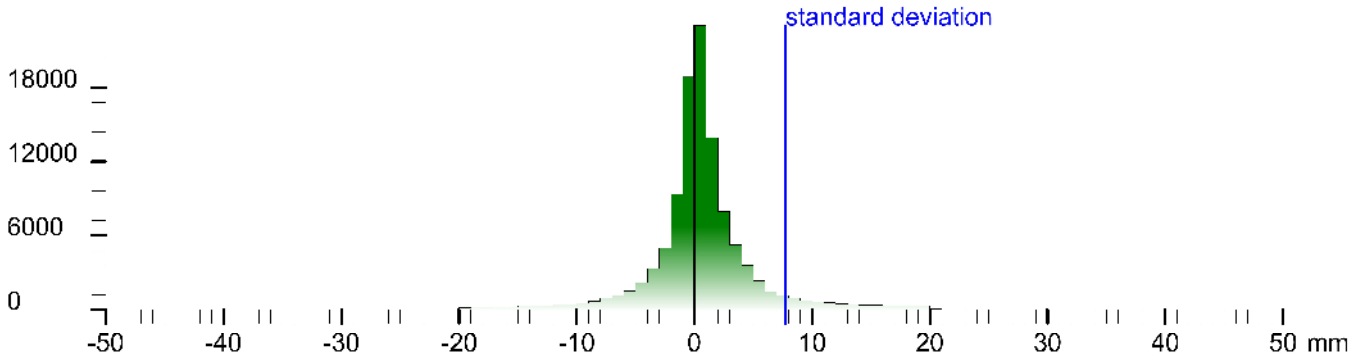
Scan position is member of group(s):
Status registration '[102h] registered with cloud to cloud'
Registration matrix:

```
0.771153 -0.636649 -0.000506 -3.1896 m
0.636649 0.771154 -0.000775 -29.2587 m
0.000884 0.000274 0.999999 -0.2085 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:7.7 mm

Deviation histogram

Points



Scan '95'

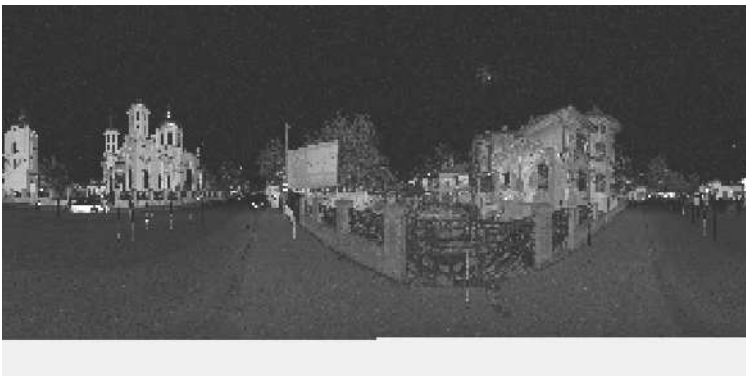
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
Scan resolution 'High' quality 'Normal'

Metadata	Value
----------	-------

comment
operator

```
Sensor: 3100 *barometric transition rotation gps
Barometer: 1.000651 bar * 05.416 m
nav translation: 10.6885 m 25.8045 m 104.5658 m accuracies: 19.2323 m * 9.2323 m 0.0000 m
nav rotation: 0.0000 0.0000 0.17334s accuracies: 0.0000 0.0000 1s.0000
upside-down: no
GPS lat:44.943066 long:26.029207 satellites:6 height:185.3m hddop:1.7 vddop:2.3m hacc:0.9m vacc:5.7 flags:G3 'stand alone 3D solution'
north:1977084.109 m east:423410.930 m zone:35T
Initial pre position (3.o. tocoor)
0.741 -0.671 0.000 -6.666
0.671 0.741 0.000 -6.6721
0.000 0.000 1.000 -77.146
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '96'

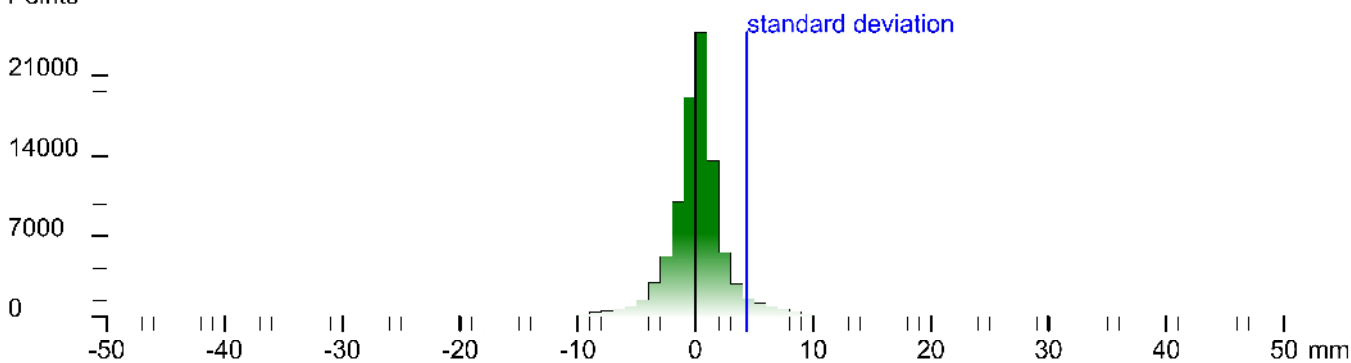
Scan position is member of group(s):
Status registration '[102h] registered with cloud to cloud'
Registration matrix:

```
0.656063 -0.754705 -0.000126 23.2640 m  
0.754705 0.656065 -0.000837 -27.5280 m  
0.000715 0.000453 0.999999 -0.1739 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:4.4 mm

Deviation histogram

Points



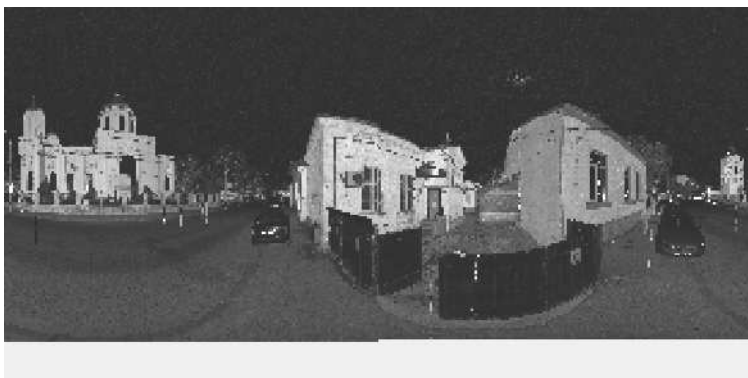
Scan '96'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Scan position: 44.943105 long: 26.029535 satellites: 6 height: 186.3m hdx: 2.1 vdc: 2.8m hacc: 5.3 m vacc: 8.2 flags: G3 'stand alone 3D solution'  
north: 197.988 / 61 m east: 423.436, 867 m zero: 35T  
Initial pre position (3.o. t.coord):  
0.616 -0.788 0.000 -62.745  
0.768 0.816 0.000 -62.745  
0.000 0.000 1.000 -76.887  
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '97'

Scan position is member of group(s):

Status registration '[102h] registered with cloud to cloud'

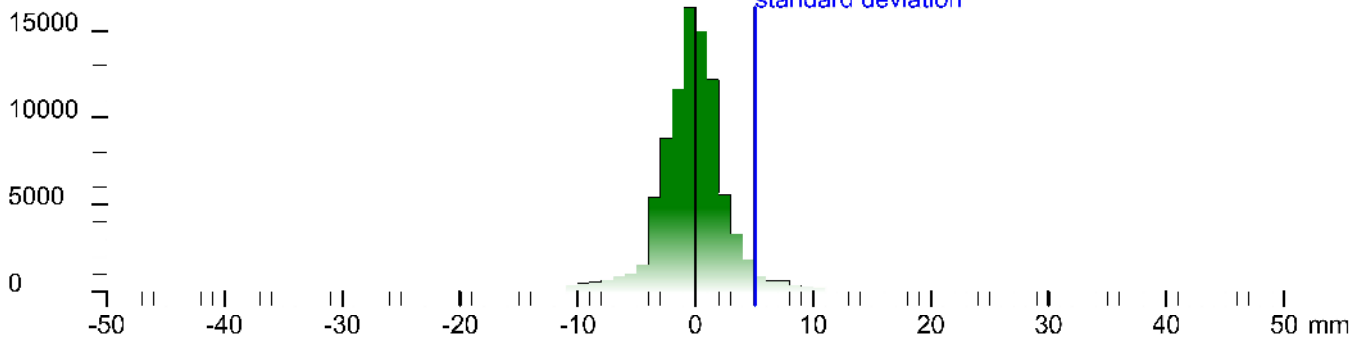
Registration matrix:

```
0.997056 -0.076667 -0.000307 38.0112 m
0.076666 0.997057 -0.001015 -26.0338 m
0.000385 0.000988 0.999999 -0.1616 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:5.1 mm

Deviation histogram

Points



Scan '97'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: full 1.908sec 303° manual 1.48:107 manual 97' opti' Bw 8' V 6' manual Bw 8' V 6' opti' for data "compensator" in use on side 27 source "Point" for manual surface registration - used in data file "1746_181" for 1 20' Aug 1940  
Sensor  
sensors: 3100 *barome or transition rotation gps  
Barometer: 1.000492 bar / 08.756 m  
nav translation: 0.0000 m 0.0000 m 105.1079 m accuracies: 5.2375 m 5.2375 m 3.0000 m  
nav rotation: 0.0000 0.0000 0.0000 Sb 1.8260 accuracies: 0.0000 0.0000 1s.0000  
upside-down: no  
GPS lat:44.943127 long:26.029716 satellites:5 height:185.4m hhdop:2.3 vhdop:3.6m hacc:8.5m vacc:8.7 flags:G3 'stand alone 3D solution'  
north:1977390.709 m east:423451.188 m zone:35T  
Initial pre position (3-coo. tocoor):  
0.990 -0.122 0.000 / 6.756  
0.42 0.990 0.000 -62.745  
0.000 0.990 1.000 -76.607  
0.000 0.990 0.000 1.000
```

Level system info: dynamic compensator available.



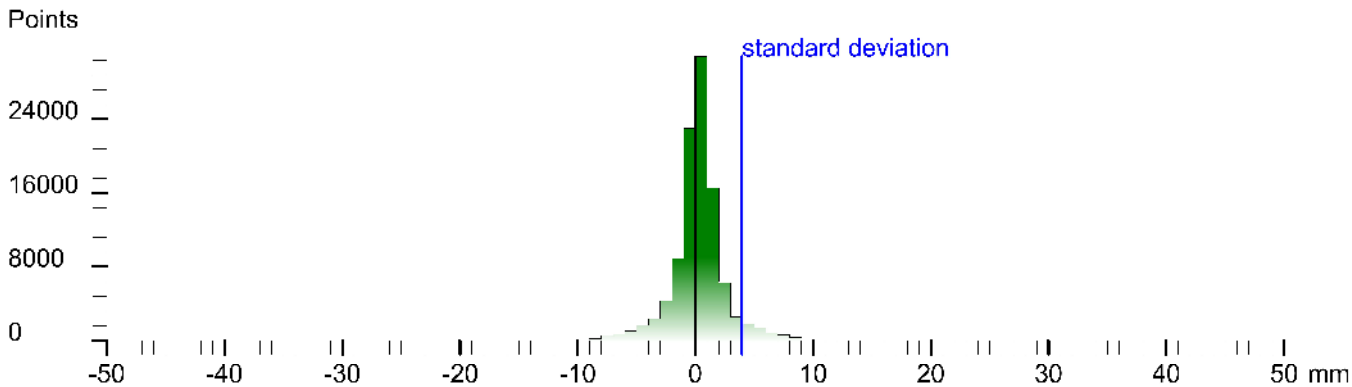
Scan position '99'

Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```
-0.925616 -0.378464 0.000082 -15.9274 m
0.378464 -0.925616 -0.000705 -3.1591 m
0.000342 -0.000621 1.000000 0.0551 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:4.0 mm

Deviation histogram



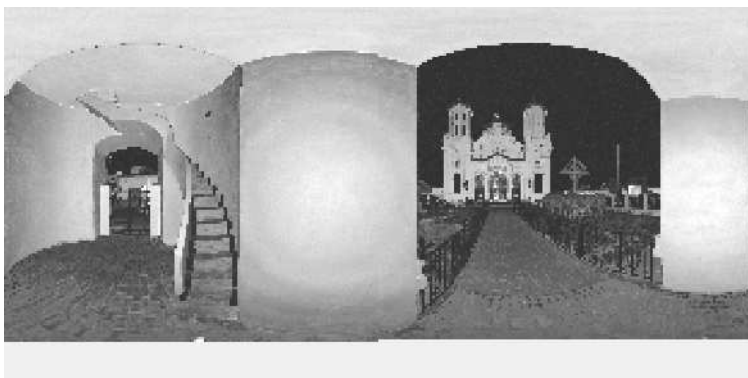
Scan '99'

Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: full 1.928x0.303 m (width: 1.48; height: 0.22) (height: 8.716 m) (width: 8.716 m) (position: 0.000 0.000 0.000) (rotation: 0.000 0.000 0.000) (scale: 1.000) (sensor: Z+F IMAGER 5016) (firmware: 9.0.3.6562-0) (serial: 5016-0100) (scan resolution: High) (quality: Normal) (operator: ) (comment: ) (date: ) (time: ) (location: ) (altitude: ) (width: 1.48) (height: 0.22) (depth: 0.303)
Sensor
sensors: 3100 *barometer/transition rotation gps
Barometer: 0.999726 bar /13.196 m
nav translation: 0.0000 m 0.0000 m 112.9837 m accuracies: 5.1000 m 5.1000 m 0.0000 m
nav rotation: 0.0000 0.0000 *98.4050 accuracies: 0.0000 0.0000 1s.0000
upside-down: no
GPS lat:44.943405 long:26.029770 satellites:3 height:236.7m hhdop:3.3 vhdop:1.0m hacc:23.0m vacc:10.4 tags:G2 *stand alone 2D solution
north:1977121.284 m east:423456.527 m zone:35T
Initial pre position (0:indoor)
-0.949 -0.316 0.000 16.756
0.316 -0.949 0.000 -52.745
0.000 0.000 1.000 -66.728
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Labels

No labels stored in project

Links

No links stored in project

Summary

Number of scans: 117 used in 117 scan positions

Point clouds: 0

Scans with color: 0 mapped 0

Scans with thermal data: 0 mapped 0

Scans with errors: 1 warnings: 0 messages: 0

Missed or corrupted scans files: 0

Scanners used in the project: 5016-0100

0 known targets used

0 targets used in 0 of 117 scan positions

First scan taken at: 20.4.2021 08:29::12 last scan at: 23.4.2021 11:14:42

Duration: 3d 2h 45min 30sec