

Project report

Date: Thu Aug 5 2021 16:31:26
Build with: Z+FLaserControl 9.0.2.24038
Project: Crucea Eroilor Caraiman
Master scan position: 1

82 of 87 scan positions used for registration.

82 of 87 scans registered.

Quality standard deviation of the cloud to cloud registration

d:3.16 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 '[23h] preregistered'
Registration matrix:

0.998916	-0.046556	0.000000	0.0000 m
0.046556	0.998916	0.000000	0.0000 m
0.000000	0.000000	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

```

Scanner: z_f_5016
Sensor:
sensors: 3100 *barometric:translator:rotation:gps
Barometer: 0.778848 bar 2164.7 m
nav:translation: 0.0000 m 0.0000 m 2163.7693 m accuracies: 5.1000 m 5.1000 m 0.0005 m
nav:rotation: 0.00000 0.00000 557.3376 accuracies: 0.00000 0.00000 114.4383
upside-down: no
GPS:lat:45.16023 long:25.497419 satellites:5 height:2327.1 m hdrop:2.0 vdoor:3.6 m hacc:5.6 m vacc:10.0 tags:G3 *stand alone 3D solution
north:5030265.074 m east:392433.976 m zone:35T
Initial pre position (3coo,ttocor):
0.999 -0 0-7 0,000 0,000
0,047 0,999 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.



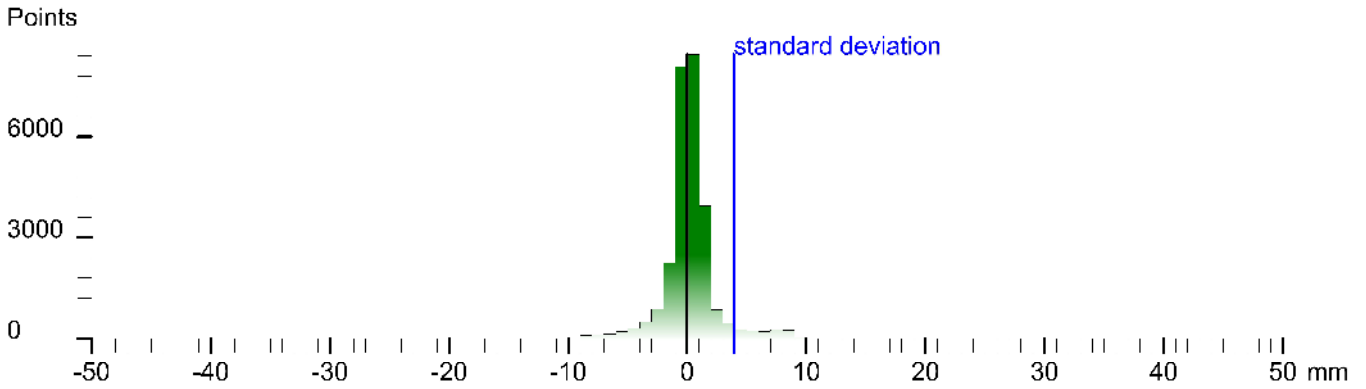
Scan position '10'

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

```
-0.955021 -0.296539 -0.000333 9.7103 m  
0.296539 -0.955021 0.000500 -3.5031 m  
-0.000466 0.000378 1.000000 8.1890 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:3.9 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	

```
Scan comment: null  
Sensor  
sensors: 3100 *barome or transition rotation gps  
Barometer: 0.778010 bar 2173.34 m  
nav translation: 0.9483 m -0.9379 m 2172.9802 m accuracies: 5.7796 m 5.7795 m 0.0000 m  
nav rotation: 0.0000 0.0000 *32.764 / accuracies: 0.0000 0.0000 1s,0.0000  
upside-down: no  
GPS lat:45.15093 long:25.497585 satellites:3 height:2336.8 m hdop:21.5 vdop:2.3m fhdop:12.0m vhdop:11.0 flags:G3 's and sbrno 3D solution'  
north:5030261 / 38 m east:382416.885 m zone:35T  
Initial pre position (3-coo. tocoor)  
-0.679 0.734 0.000 0.837  
-0.73 -0.679 0.000 3.417  
0.000 0.000 1.000 -2.173  
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'

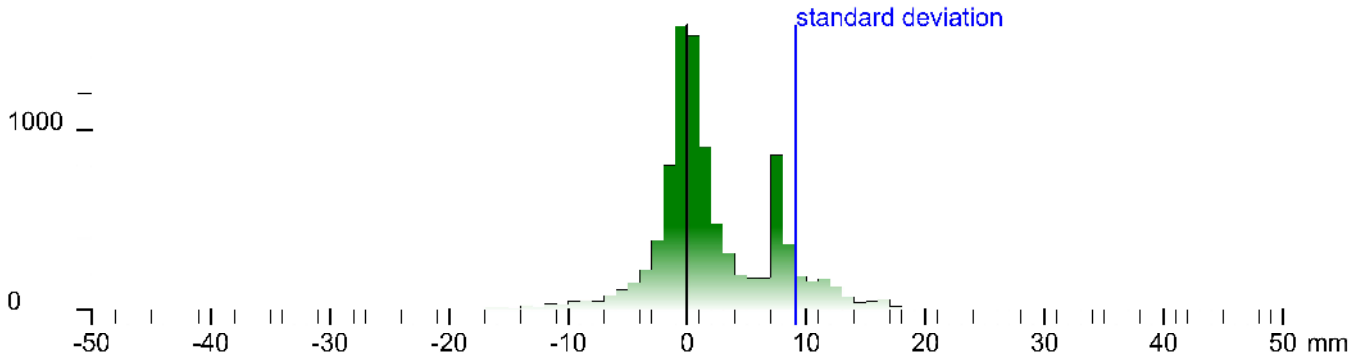
Registration matrix:

-0.616784	0.787133	-0.000256	8.5950 m
-0.787133	-0.616784	0.000139	-3.7869 m
-0.000049	0.000287	1.000000	10.0101 m
0.000000	0.000000	0.000000	1.0000

Result registration cloud to cloud standard deviation:9.1 mm

Deviation histogram

Points



Scan '11'

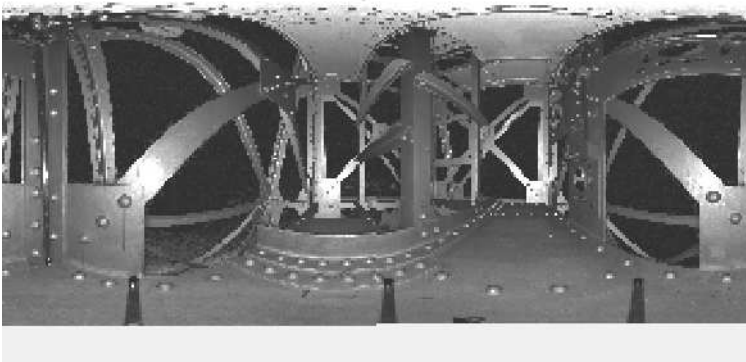
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

Scan comment: null
Sensor
sensors: 3100 * barome or transition rotation gps
Barometer: 0.777966 bar 2173.78 m
nav translation: 2.6672 m 9.6357 m 2173.5959 m accuracies: 10.1195 m * 0.1135 m 0 0000 m
nav rotation: 0.0000 0 0000 * /6.233 / accuracies: 0.0000 0.0000 1s.0000
upside-down: no
GPS lat:45.16006 long:25.497519 satellites:4 height:2336.3 m hdop:1.2 vldop:3.3 m hacc:4.7 m vacc:10.0 tags:G3 'stand alone 3D solution'
north:5030263.231 m east:382411.703 m zone:35T
Initial pre position (3-coo, t-coor):
-0.998 0.066 0.000 -1.51
-0.068 -0.066 0.000 3.52
0.000 0.000 1.000 -1.557
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'

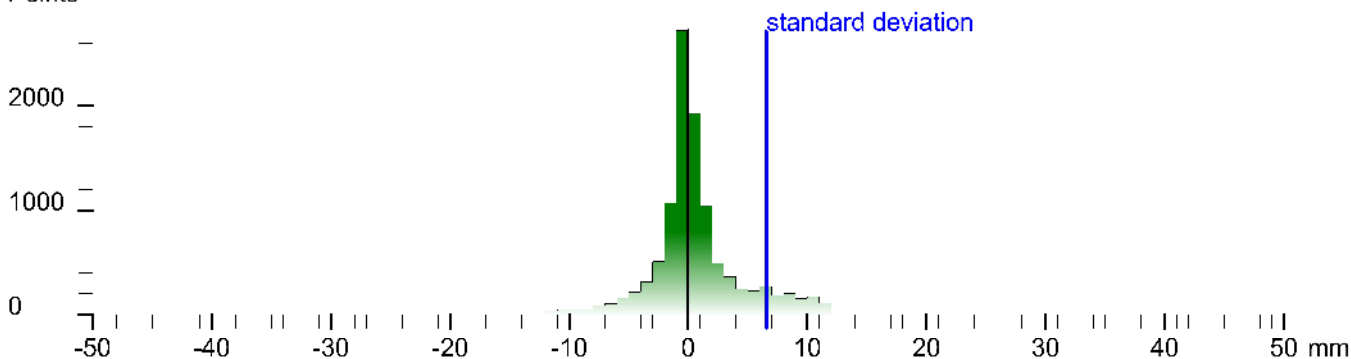
Registration matrix:

```
0.999108 -0.042242 -0.000050 7.9791 m
0.042242 0.999108 -0.000284 -2.1026 m
0.000062 0.000282 1.000000 10.0150 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:6.6 mm

Deviation histogram

Points



Scan '12'

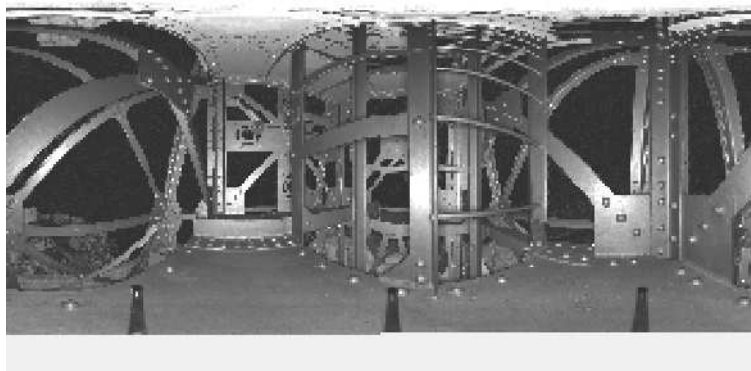
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: full 1.500x0.300 m range: 1.40 m 2 scans: 12 points Cloud to Cloud registration matrix: [102h] registered with cloud to cloud  
Sensor  
sensors: 3100 *barometric transition rotation gps  
Barometer: 0.777908 bar 2174.39 m  
nav translation: -3.8784 m 2.0917 m 2172.9487 m accuracies: 0.2271 m 0.2271 m 0.0000 m  
nav rotation: 0.0000 0.0000 220.4662 accuracies: 0.0000 0.0000 1s.0000  
upside-down: no  
GPS lat:45.16091 long:25.497507 satellites:7 height:2335.5 m hdop:0.9 vdoor: 1.9 m hacc:4.6 m vacc:8.3 flags:G3 's are above 3D solution'  
north:5030265.781 m east:382410.855 m zone:35T  
Initial pre position (3-coor):  
-0.761 -0.649 0.000 -2.043  
0.849 -0.781 0.000 5.724  
0.000 0.000 1.000 -2.205  
0.000 0.000 0.000 1.000
```

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



Scan position '13'

Scan position is member of group(s):

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

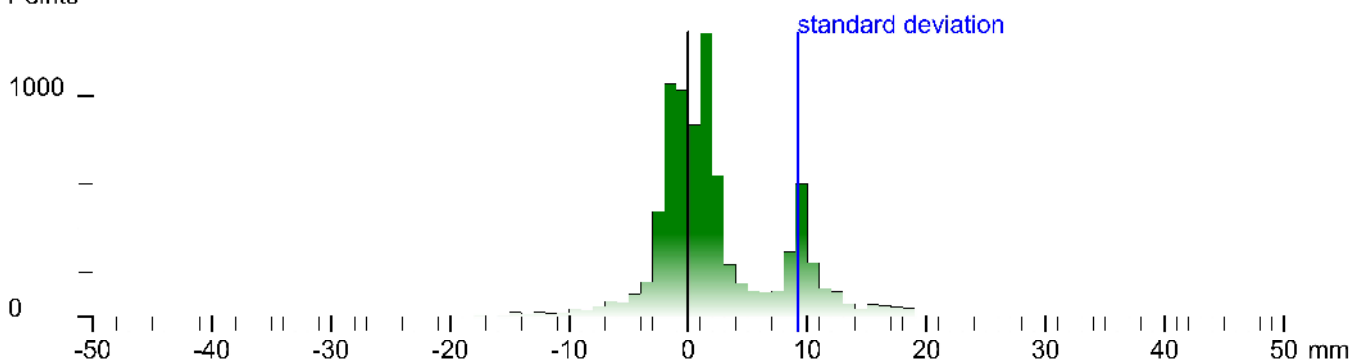
Registration matrix:

```
0.949858 0.312684 0.000687 9.0312 m
-0.312684 0.949858 -0.000064 -2.4797 m
-0.000672 -0.000154 1.000000 12.1650 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:9.2 mm

Deviation histogram

Points



Scan '13'

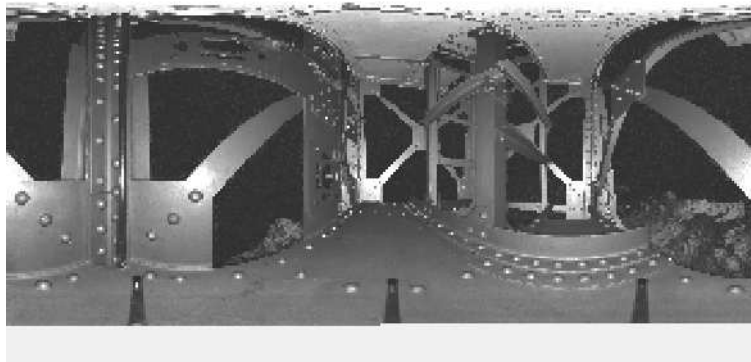
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: full 1.908x0.303 m (width: 1.46 m) 30 seconds 15° pitch "Creaux Eclair" Grid scan mode: "Creaux Eclair" Grid scan speed: 1000 mm/s "New" status: "20" scan: "Scan" position: "A" file: "scan_13" quality: "High" resolution: "4" format: "ST" format: "ST" for: "3407"
Sensor
sensors: 3100 *barome or transition rotation gps
Barometer: 0.777727 bar 2176.26 m
nav translation: -2.2807 m -2.7733 m 2175.6780 m accuracies: 6.9115 m 6.6115 m 0.0005 m
nav rotation: 0.0000 0.0000 334.9391 accuracies: 0.0000 0.0000 1s.0000
upside-down: no
GPS lat: 45.15997 long: 25.49754 satellites: 7 height: 2339.1 m hdop: 1.0 vdoor: 1.7 m hacc: 4.1 m vacc: 7.6 flags: G3 's are above 3D solution'
north: 5030261.821 m east: 382413.768 m zone: 35T
Initial pre position (3-coo. tocoor):
0.906 -0.474 0.000 0.860
0.424 0.906 0.000 1.892
0.000 0.000 1.000 0.525
0.000 0.000 0.000 1.000
```

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



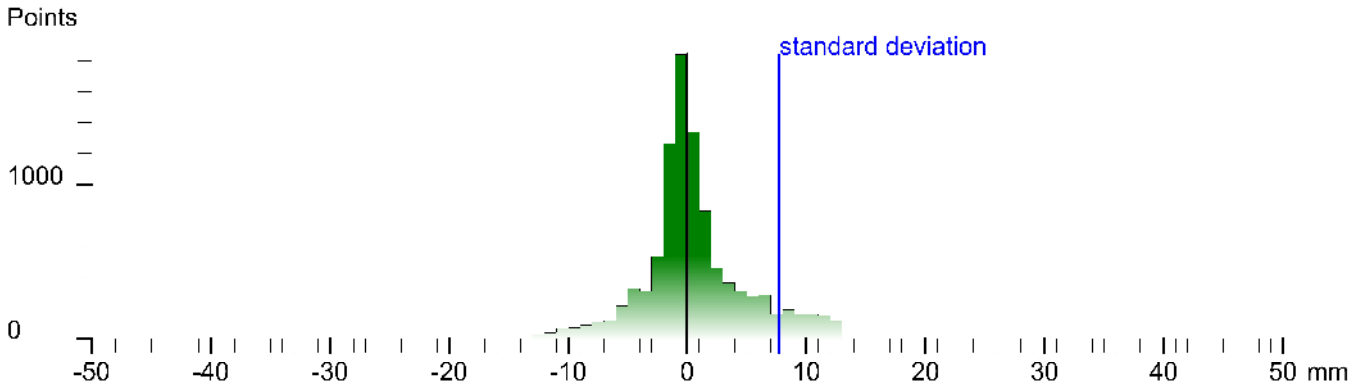
Scan position '14'

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

```
-0.710213 -0.703987 0.000713 7.5224 m
0.703987 -0.710213 -0.000864 -3.4553 m
0.001114 -0.000112 0.999999 12.1639 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 7.7 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: null
Sensor
sensors: 3100 *barome or transition rotation gps
Barometer: 0.777729 bar 2176.24 m
nav translation: -3.4117 m -0.1885 m 2176.3728 m accuracies: 5.3457 m 5.3457 m 0.0000 m
nav rotation: 0.0000 0.0000 2/8.8978 accuracies: 0.0000 0.0000 1s.0000
upside-down: no
GPS lat:45.16006 long:25.497513 satellites:4 height:2343.7 m hdop:6.3 vdoop:5.7 m hacc:6.9m vacc:9.5 flags:G3 's are above 3D solution'
north:5030263.240 m east:382411.255 m zone:35T
Initial pre position (3-coor):
0.51 -0.988 0.000 0.418
0.950 0.151 0.000 1.703
0.000 0.000 1.000 1.279
0.000 0.000 0.000 1.000
```

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



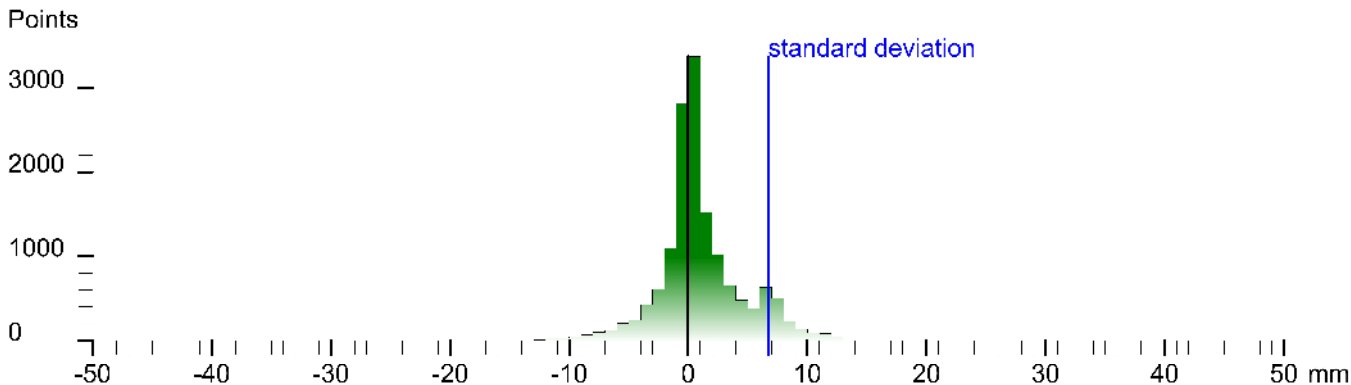
Scan position '15'

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

```
-0.829760 -0.558120 -0.001259 8.6211 m
0.558121 -0.829759 -0.000901 -3.7756 m
-0.000542 -0.001451 0.999999 14.3142 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:6.7 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: '15' status: '15' ...  

Sensor  

sensors: 3100 *barome or transition rotation gps  

Barometer: 0.777503 bar 2178.57 m  

nav translation: -3.6853 m 3.8754 m 2177.936 m accuracies: 7.0857 m 7.0857 m 0.0005 m  

nav rotation: 0.0000 0.0000 334.9270 accuracies: 0.0000 0.0000 16.0000  

upside-down: no  

GPS lat:45.15093 long:25.497561 satellites:5 height:2345.7 m hdop:2.0 vdoop:2.8 m hacc:6.3 m vacc:7.8 flags:G3 's are above 3D solution'  

north:5030261.75 m east:382441.955 m zcorr:35T  

Initial pre position (3o..tooor)  

0.906 -0.474 0.000 2.104  

0.424 0.906 0.000 1.424  

0.000 0.000 1.000 2.043  

0.000 0.000 0.000 1.000
```

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



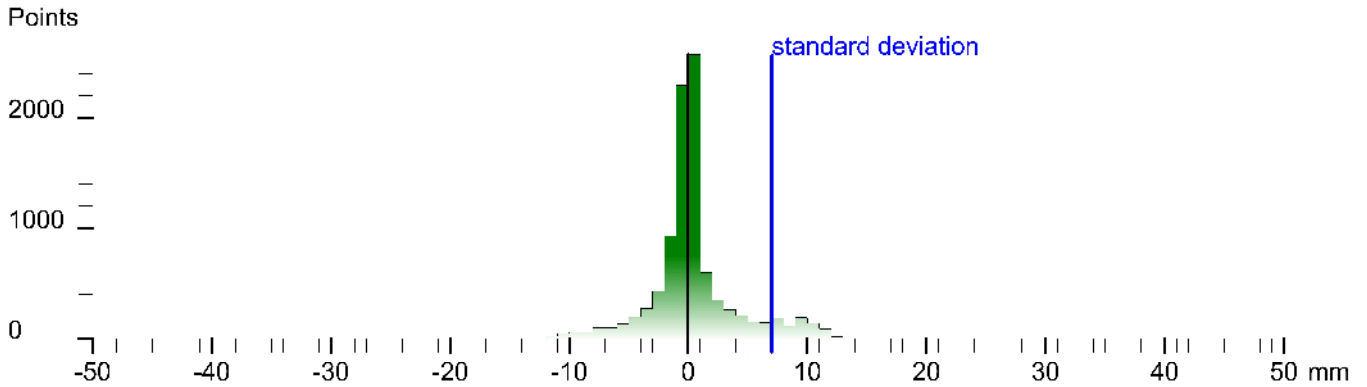
Scan position '16'

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

-0.939239	-0.343266	0.000647	8.0017 m
0.343265	-0.939239	-0.000820	-2.1729 m
0.000889	-0.000549	0.999999	14.3156 m
0.000000	0.000000	0.000000	1.0000

Result registration cloud to cloud standard deviation:7.0 mm

Deviation histogram



Scan '16'

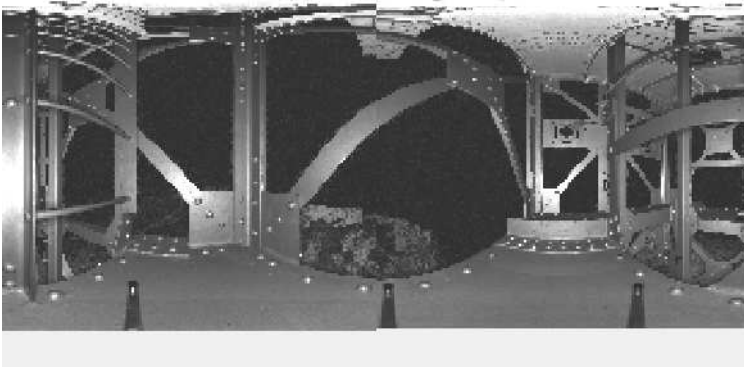
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```

Sensor:
sensors: 3100 *barometric/transition rotation/gps
Barometer: 0.777500 bar 2178.6 m
nav translation: 2.0425 m 0.5890 m 2178.107 m accuracies: 0.1744 m 0.1744 m 0.0006 m
nav rotation: 0.0000 0.0000 * 93.8262 accuracies: 0.0000 0.0000 1s:0.0000
upside-down: no
GPS lat:45.16027 long:25.497520 satellites:6 height:23+6.4 m hdop:1.3 vdoa:2.3 m hacc:5.8m vacc:9.8 flags:G3 's:arc:stbr: 3D solution'
north:5030265.347 m east:382411.892 m zora:35T
Initial pre position (3-coo.tccor):
-0.689 0.775 0.000 -1.034
-0.725 -0.889 0.000 5.281
0.000 0.000 1.000 2.964
0.000 0.000 0.000 1.000
    
```

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



Scan position '19'

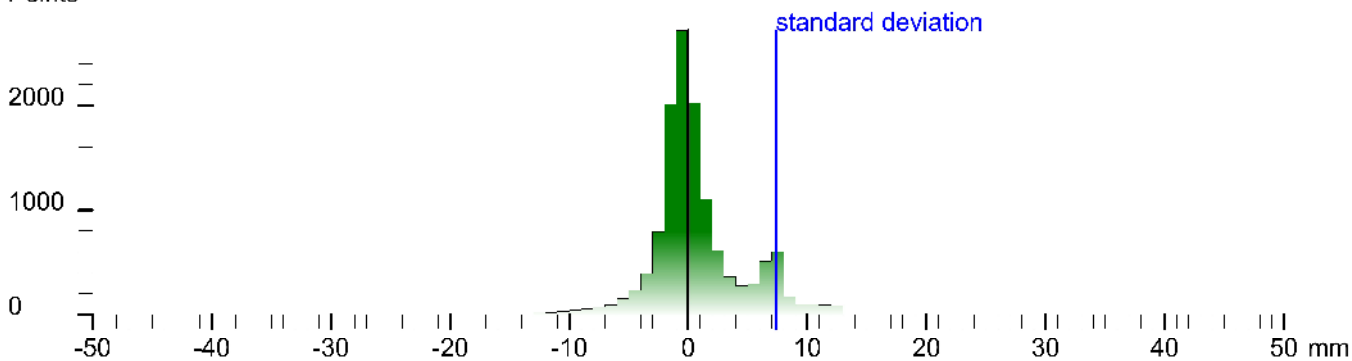
Scan position is member of group(s):
Status registration '[102h] registered with cloud to cloud'
Registration matrix:

```
-0.798559 0.601915 0.001762 8.6194 m  
-0.601916 -0.798560 -0.000028 -3.7626 m  
0.001390 -0.001082 0.999998 18.6046 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:7.3 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 comment: full 1908000 3031 mm:160 1908000 160 mm:1908000 160 mm:1908000 160 mm:1908000 160 mm:1908000 160 mm:1908000 160 mm:1908000 160 mm:1908000 160 mm:1908000 160 mm:1908000  
Sensor  
sensors: 3100 *barometric transition rotation gps  
Barometer: 0.777197 bar 2181.73 m  
nav translation: 2.4604 m 0.8553 m 218 * .1199 m accuracies: 0.156 m 0.156 m 0.0000 m  
nav rotation: 0.0000 0.0000 221.46 * 1 accuracies: 0.0000 0.0000 1s:0.0000  
upside-down: no  
GPS lat:45.16005 long:25.497543 satellites:5 height:2345.3 m hdop:2.5 vdop:2.7 m hacc:7.3m vacc:10.0 tags:G3 *stand alone 3D solution  
north:5030263.185 m east:382413.613 m zone:35T  
Initial pre position (300. tooor)  
-0.749 -0.667 0.000 1.980  
0.882 -0.7-9 0.000 -0.883  
0.000 0.000 1.000 5.967  
0.000 0.000 0.000 1.000
```

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



Scan position '2'

Scan position is member of group(s):

Status registration '[122h] preregistered with cloud to cloud'

Registration matrix:

```
-0.972123  0.234464  -0.001895  10.3868 m
-0.234462  -0.972125  -0.001081  -5.4014 m
-0.002096  -0.000607  0.999998   8.1236 m
0.000000   0.000000   0.000000   1.0000
```

Scan '2'

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

Scan resolution 'High' quality 'Normal'

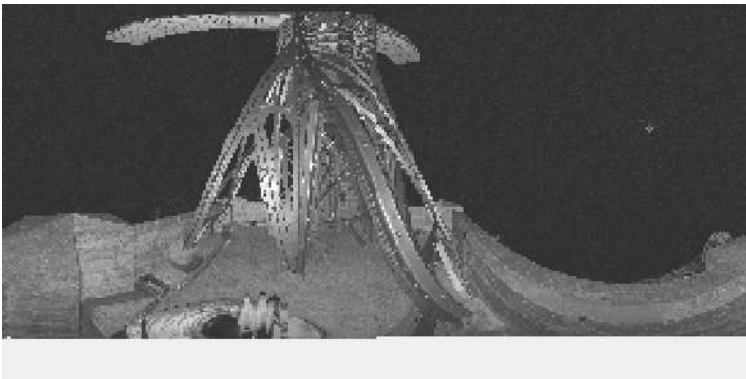
Metadata **Value**
comment
operator

Scan position: 2011-10-26 11:05:59.403 camera: 1.48 sensor: Z+F IMAGER 5016 scanner: Z+F IMAGER 5016 serial: 5016-0100 firmware: 9.0.3.6562-0 status: preregistered with cloud to cloud registration: [122h] preregistered with cloud to cloud quality: high resolution: normal scan resolution: normal

Sensor

```
sensors: 3100 *barometric transducer rotation gps
Barometer: 0.777784 bar 2175.68 m
nav translation: 6.4363 m 2.4270 m 2175.1533 m accuracies: 8.1970 m 9.1970 m 0.0000 m
nav rotation: 0.00000 0.00000 * 73.3173 accuracies: 0.00000 0.00000 15.00000
upstop-down: 0
GPS lat: 45.415989 long: 25.497547 satellites: 7 height: 2933.6 m hdop: 1.3 vdox: 2.1 m haec: 4.2m vacc: 7.8 flags: G3 'static alone 3D solution'
north: 5030261.070 m east: 382443.902 m zone: 35T
Initial pre position (3-coor):
-0.993 0 116 0.000 1.000
-0.116 -0.893 0.000 1.000
0.000 0.000 1.000 0.000
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



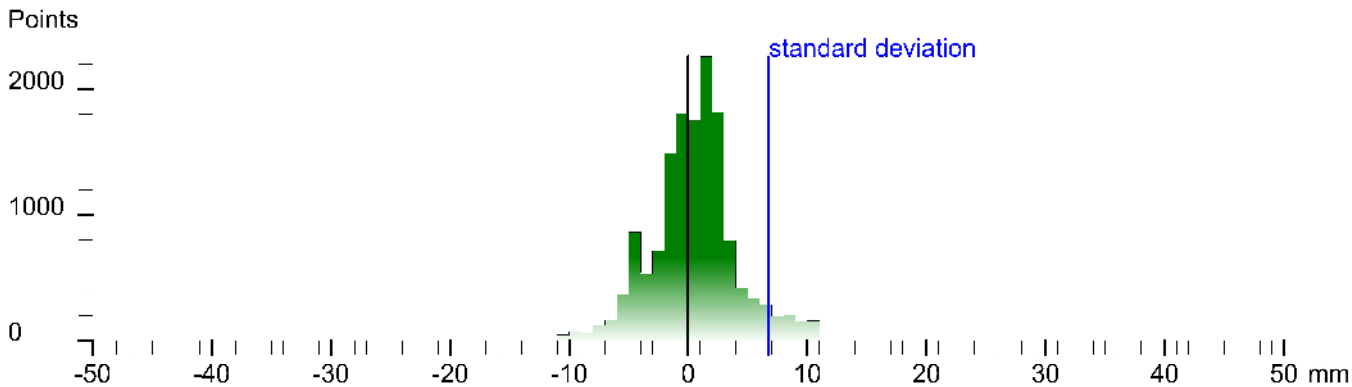
Scan position '22'

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

```
-0.329778 -0.944058 0.001325 7.5993 m
0.944059 -0.329779 -0.000263 -3.4482 m
0.000685 0.001164 0.999999 20.7622 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:6.8 mm

Deviation histogram



Scan '22'

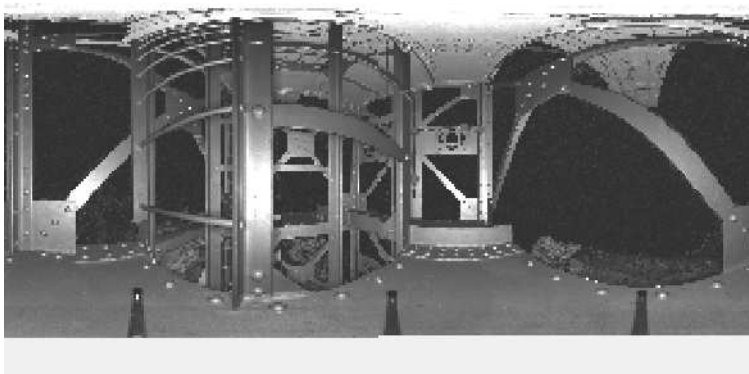
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

Scan information: 148000000 points; 148:22; scanid: '22'; type: 'Cloud Edge'; Cloud ID: '0'; registration: 'cloud to cloud'; registration status: 'registered with cloud to cloud'; registration standard deviation: 6.8 mm; registration quality: 'High'; scan resolution: 'Normal'; scan quality: 'Normal'; scan resolution: 'High'; scan quality: 'Normal'

Sensor:
 sensors: 3100 *barometer; transition; rotation; gps
 Barometer: 0.776084 bar; 2183.33 m
 nav translation: -3.6922 m; 3.2287 m; 2183.6580 m; accuracies: 5.1672 m; 5.1672 m; 0.0005 m
 nav rotation: 0.0000 0.0000 0.0000 530.6099; accuracies: 0.0000 0.0000 16.0000
 up/down: no
 GPS: lat: 45.15095; long: 25.49740; satellites: 6; height: 2346.5 m; hdop: 1.6; vhdop: 2.1 m; hacc: 5.9 m; vacc: 8.8; flags: G3; s; a; m; a; b; n; o; 3D solution
 north: 5030260.716 m; east: 382410.163 m; zone: 35T
 Initial pre position (3-coor):
 0.911 -0.417 0.000 -2.764
 0.412 0.911 0.000 0.628
 0.000 0.000 1.000 8.605
 0.000 0.000 0.000 1.000

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



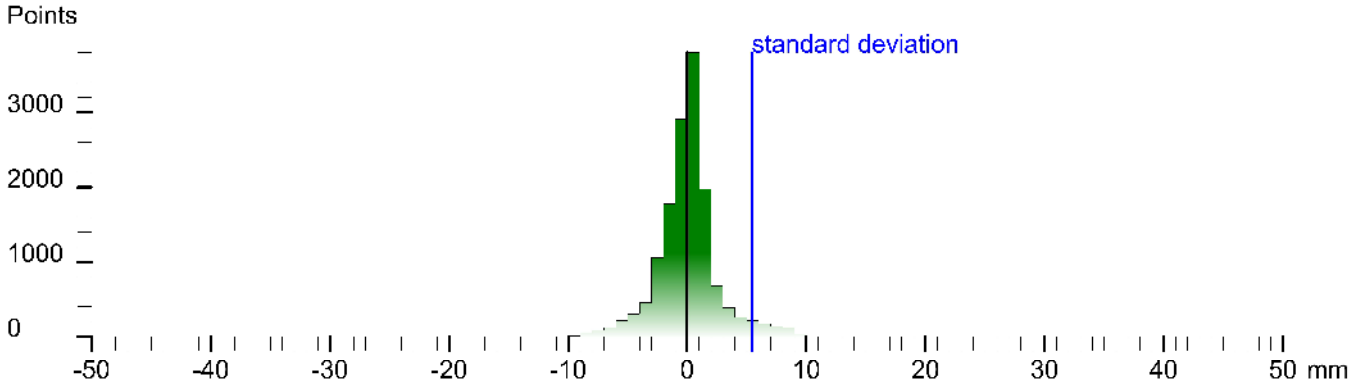
Scan position '24'

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

```
-0.980243 -0.197795 0.001251 8.0434 m
0.197793 -0.980244 -0.001072 -2.1875 m
0.001438 -0.000803 0.999999 22.9127 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:5.4 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	

```
Scan comment: full 100% scan of the 140m x 24m square '24' with 'Cloud Edge' Cloud-to-Cloud registration matrix. The registration matrix is a 4x4 matrix with the following values:
Sensor
sensors: 3100 * barometer transition rotation gps
Barometer: 0.776840 bar 2185.4 m
nav translation: 0.0598 m -1.0968 m 2185.7305 m accuracies: 5.6547 m 5.6547 m 0.0000 m
nav rotation: 0.0000 0.0000 0.0000 * 7.24809 accuracies: 0.0000 0.0000 15.0000
upside-down: no
GPS lat:45.16091 long:25.497480 satellites:6 height:2346.3 m hdop:1.5 vdoop:1.6 m hacc:7.4 m vacc:8.2 flags:G3 's are above 3D solution'
north:5030265.830 m east:382438.766 m zone:35T
Initial pre position (3-coor):
-0.981 0.131 0.000 -4.55
-0.131 -0.981 0.000 5.784
0.000 0.000 1.000 10.577
0.000 0.000 0.000 1.000
```

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



Scan position '27'

Scan position is member of group(s):

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

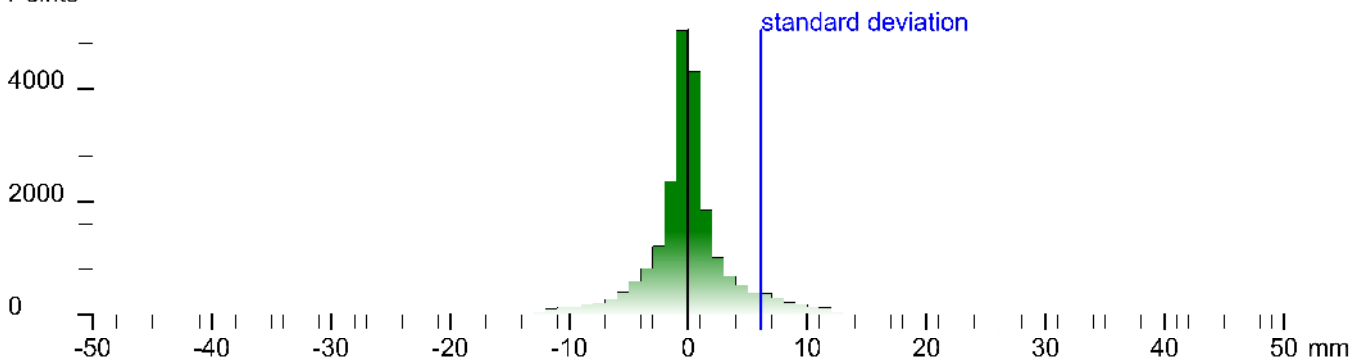
Registration matrix:

```
-0.931742  0.363123  0.000641  7.2220 m  
-0.363124 -0.931740 -0.001740 -5.4845 m  
-0.000035 -0.001854  0.999998  27.1550 m  
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation:6.1 mm

Deviation histogram

Points



Scan '27'

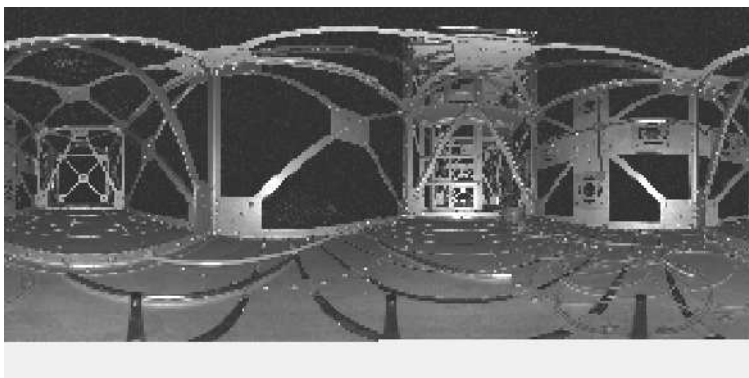
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Scan comment: full LPSBuster 303 - model: 148-27 - scan: 27 - type: Cloud to Cloud - sensor: Z+F IMAGER 5016 - serial: 5016-0100 - firmware: 9.0.3.6562-0 - resolution: High - quality: Normal - scan resolution: 0.4 mm - scan type: Cloud to Cloud  
Sensor  
sensors: 3100 * barometer translation rotation gps  
Barometer: 0.776442 bar 2189.52 m  
nav translation: -2.9930 m -3.305° m 2189.22° m accuracies: 7.2216 m 7.2216 m 0.0000 m  
nav rotation: 0.0000 0.0000 0.0000 04.6:60 accuracies: 0.0000 0.0000 1s:0.0000  
upside-down: no  
GPS lat:45.15974 long:25.497526 satellites:7 height:2354.5 m hdop:1.3 vdoor: 1.5 m hacc:5.6m vacc:7.4 flags:G3 's are alone 3D solution'  
north:5030268.706 m east:382712.228 m zone:35T  
Initial pre position (3.o. t.coor):  
-0.753 0.967 0.000 -0.674  
-0.987 -0.255 0.000 -0.636  
0.000 0.000 1.000 14.071  
0.000 0.000 0.000 1.000
```

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



Scan position '38'

Scan position is member of group(s):

Status registration '[122h] preregistered with cloud to cloud'

Registration matrix:

-0.797362	-0.603486	-0.004541	8.1100 m
0.603501	-0.797358	-0.003173	-2.2116 m
-0.001706	-0.005270	0.999985	35.6636 m
0.000000	0.000000	0.000000	1.0000

Scan '38'

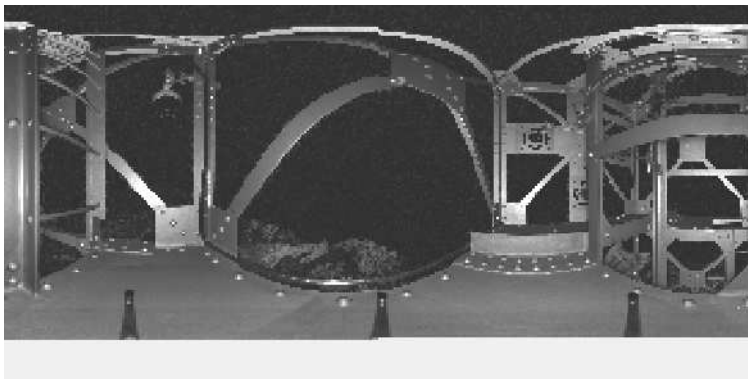
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata Value comment operator

```
base coordinates: x:1.0356e+03 y:1.0000e+04 z:1.44e+08 sensor: 38'zfs'Z+F IMAGER 5016 serial number: 5016-0100 firmware: 9.0.3.6562-0 registration: [122h] preregistered with cloud to cloud registration matrix: 0.000000 0.000000 0.000000 1.000000  
Sensor  
sensors: 3100 *barometric translation: rotation: gps  
Barometer: 0.775480 bar 2199.87 m  
nav translation: -2.0430 m -0.3687 m 2199.0715 m accuracies: 6.1539 m 6.1539 m 0.0000 m  
nav rotation: 0.00000 0.00000 0.99994 accuracies: 0.00000 0.00000 15.00000  
upside-down: no  
GPS lat:45.-16035 long:25.497524 satellites:5 height:2960.5 m hdop:1.7 vdoop:2.8 m hacc:7.9m vacc:11.0 flags:G3 'stand alone 3D solution'  
north:5030266.189 m east:382442.206 m zone:e:35T  
Initial pre position: (300,300,0)  
0.797362 -0.603486 0.004541 8.1100  
0.603501 -0.797358 -0.003173 -2.2116  
0.001706 0.005270 -0.999985 -35.6636  
0.000000 0.000000 0.000000 1.0000
```

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



Scan position '39'

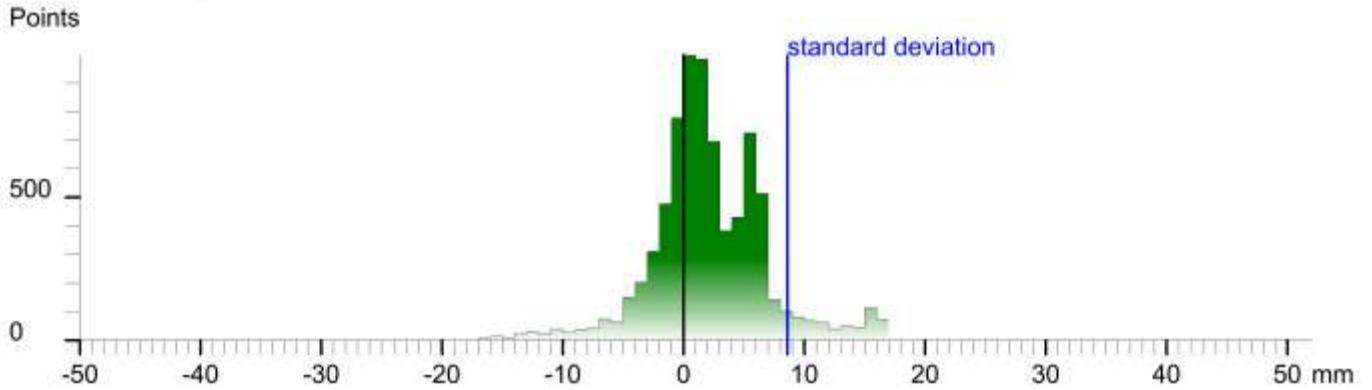
Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```

0.831746 0.555158 0.000756 8.7015 m
-0.555157 0.831747 -0.000398 -3.1724 m
-0.000850 -0.000089 1.000000 27.2112 m
0.000000 0.000000 0.000000 1.0000
    
```

Result registration cloud to cloud standard deviation:8.6 mm

Deviation histogram



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
sensors: 3100 *barometric transition rotation gps
Barometer: 0.776047 bar 2193.6 m
nav translation: 1.978 m 1.3829 m 2193.4810 m accuracies: 0.7062 m 0.7062 m 0.0005 m
nav rotation: 0.0000 0.0000 63.8242 accuracies: 0.0000 0.0000 1s.0000
upside-down: no
GPS lat:45.16042 long:25.497547 satellites:8 height:2355.1 m hdop:1.0 vdoor: 1.2m hacc:5.7m vaccc:6.6 flags:G3's airc alone 3D solution'
north:5030267.004 m east:382441.013 m zone:a:35T
Initial pre position (3-coo. tooor):
0.108 0.994 0.000 1.110
-0.990 -0.108 0.000 6.880
0.000 0.000 1.000 18.328
0.000 0.000 0.000 1.000
    
```

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



Scan position '4'

Scan position is member of group(s):

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

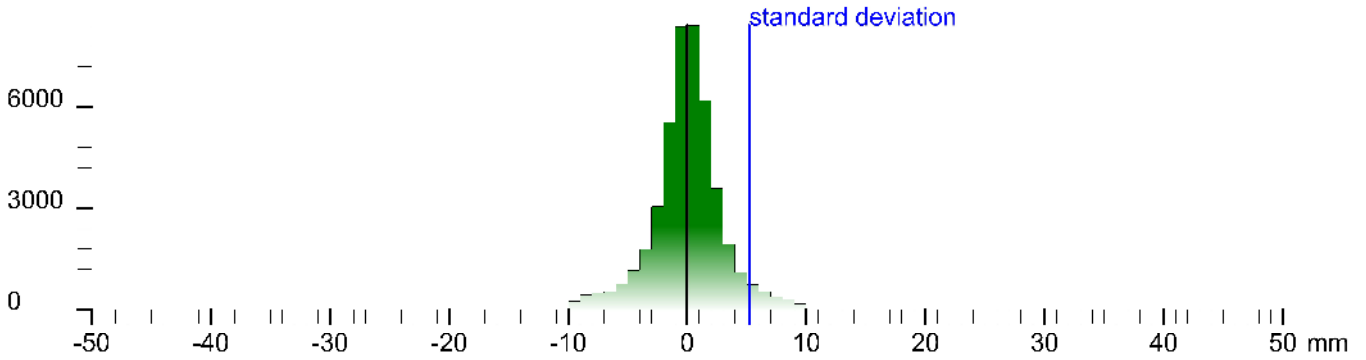
Registration matrix:

```
-0.256046 -0.966665 0.000127 5.6882 m  
0.966665 -0.256045 0.000240 -5.1073 m  
-0.000199 0.000184 1.000000 8.2878 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:5.2 mm

Deviation histogram

Points



Scan '4'

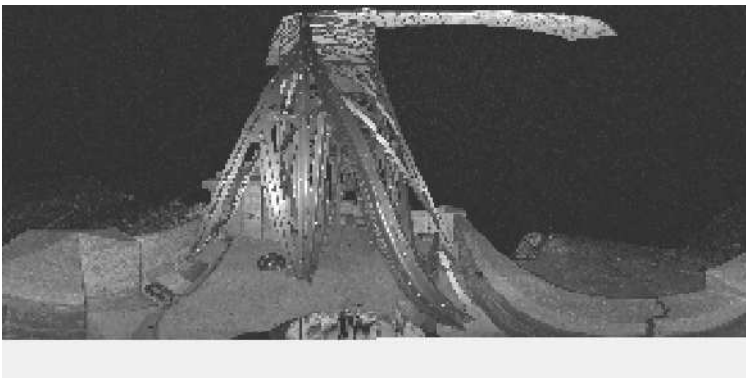
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata Value comment operator

```
Scan position: '4' [102h] registered with cloud to cloud  
Sensor  
sensors: 3100 *barometer transition rotation gps  
Barometer: 0.777822 bar 2177.35 m  
nav translation: 1.0682 m -3.6111 m 2176.5671 m accuracies: 5.7738 m 5.7738 m 0.0007 m  
nav rotation: 0.0000 0.0000 203.1300 accuracies: 0.0000 0.0000 1s.0000  
upside-down: no  
GPS lat:45.15982 long:25.497473 satellites:5 height:2332.7 m hdop:1.6 vdoop:3.3 m hacc:4.0m vacc:5.5 flags:G3 's are above 3D solution'  
north:5030288.213 m east:382438.027 m zone:35T  
Initial pre position (3co. tocoo):  
-0.990 -0.393 0.000 -4.846  
0.300 -0.920 0.000 -1.631  
0.000 0.000 1.000 1.414  
0.000 0.000 0.000 1.000
```

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



Scan position '40'

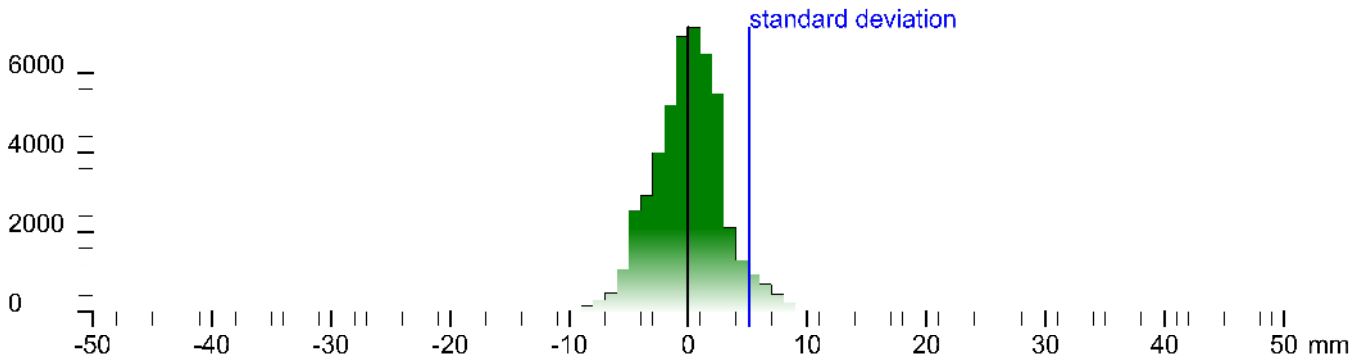
Scan position is member of group(s):
Status registration '[102h] registered with cloud to cloud'
Registration matrix:

```
0.350087 -0.936717 -0.000733 10.4331 m  
0.936717 0.350086 0.000536 -3.8063 m  
-0.000246 -0.000875 1.000000 8.9749 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:5.1 mm

Deviation histogram

Points



Scan '40'

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: 2016-11-14 19:08:40.337 m: 146.140 n: 49.760 e: 49.760  
Sensor  
sensors: 3100 *barome or transition rotation gps  
Barometer: 0.777854 bar 2177.0 m  
nav translation: 0.0000 m 0.0000 m 2176.5235 m accuracies: 5.1000 m 5.1000 m 0.0000 m  
nav rotation: 0.0000 0.0000 291.243 accuracies: 0.0000 0.0000 16.0000  
upside-down: no  
GPS lat: 45.16000 lon: 25.49750 satellites: 4 height: 2339.5 m hdop: 2.7 vdoop: 4.8 m hacc: 12.0 m vacc: 15.0 m ssgs: G3 'stand alone 3D solution'  
north: 5030262.381 m east: 382411.887 m zone: 35T  
Initial pre position (3-coo. to coord)  
0.383 -0.932 0.000 0.110  
0.932 0.383 0.000 6.858  
0.000 0.000 1.000 1.367  
0.000 0.000 0.000 1.000
```

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



Scan position '42'

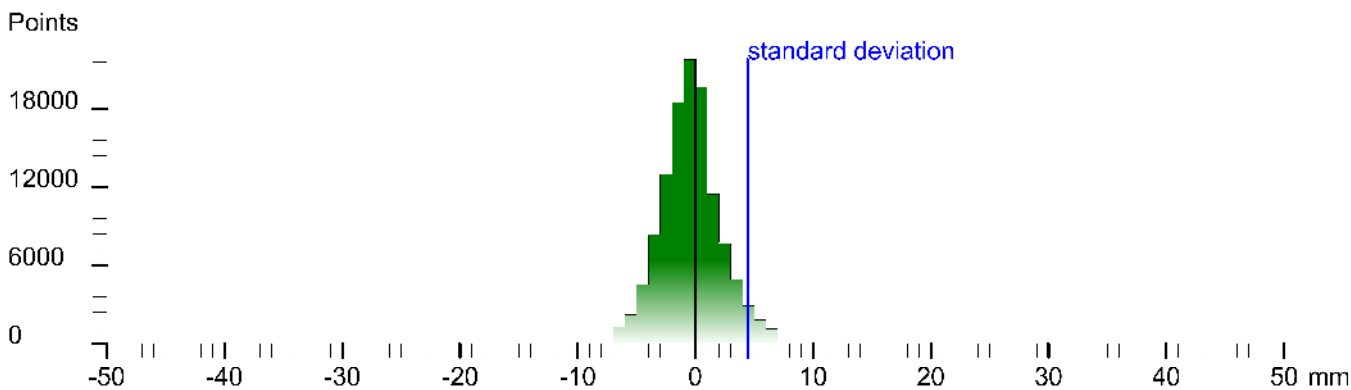
Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```

0.946133  0.323779  0.000246  7.4105 m
-0.323779 0.946133  0.000246 -5.1921 m
-0.000153 -0.000312 1.000000  8.9283 m
0.000000  0.000000  0.000000  1.0000
    
```

Result registration cloud to cloud standard deviation:4.4 mm

Deviation histogram



Scan '42'

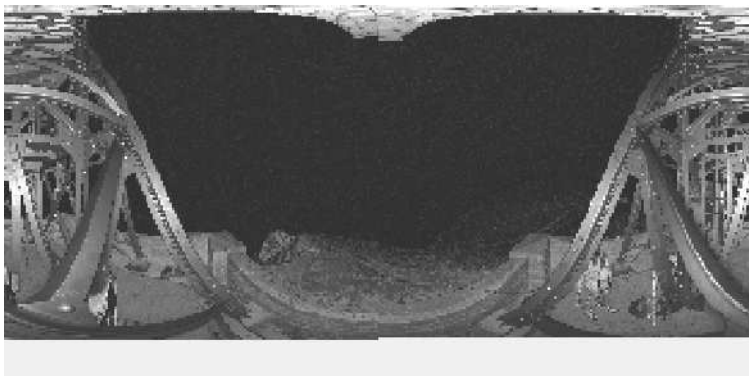
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0
 Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```

Scan position: '42' member of group(s): '102h' registered with cloud to cloud
Sensor
sensors: 3100 *barometric transition rotation gps
Barometer: 0.777746 bar 2176.06 m
nav translation: -1.0557 m 5.7752 m 2175.9811 m accuracies: 8.0683 m 8.0683 m 0.0000 m
nav rotation: 0.0000 0.0000 9.0370 accuracies: 0.0000 0.0000 1s 1.7e4s
upside-down: no
GPS lat:45.16004 long:25.497532 satellites:7 height:2340.9 m hdop:1.1 vdoop:2.6 m hacc:7.1m vacc:15.0 tags:G3 'stand alone 3D solution'
north:5030262.788 m east:382412.740 m zcra:35T
Initial pre position (3-coo. tooor):
0.988 0.157 0.000 -0.143
-0.157 0.988 0.000 2.686
0.000 0.000 1.000 0.828
0.000 0.000 0.000 1.000
    
```

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



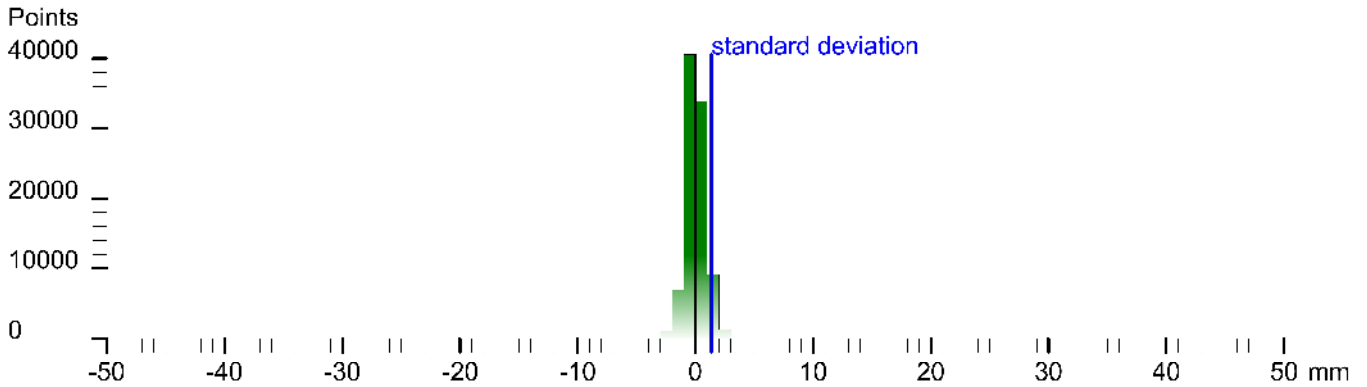
Scan position '43'

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

```
0.284817  0.958580  -0.002281  10.6314 m
-0.958582  0.284819  0.000502  -3.2579 m
0.001131  0.002043  0.999997  4.0569 m
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation: 1.4 mm

Deviation histogram



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 comment: null
Sensor
sensors: 3096 *barometric transition rotation*
Barometer: 0.777853 bar 2174.36 m
nav translation: 15.983° m -6.1822° m 2176.6138 m accuracies: 15.9286 m 13.9286 m 0.0000 m
nav rotation: 0.0000 0.0000 95.2126 accuracies: 0.0000 0.0000 15.0000
upside-down: no
Initial pre position (Girdoor)
-3.081 0.896 0.000 -5.811
-0.996 -0.08° 0.000 -3.494
0.000 0.000 1.000 1.490
0.000 0.000 0.000 1.000

Level system info: dynamic compensator available.



Scan position '44'

Scan position is member of group(s):

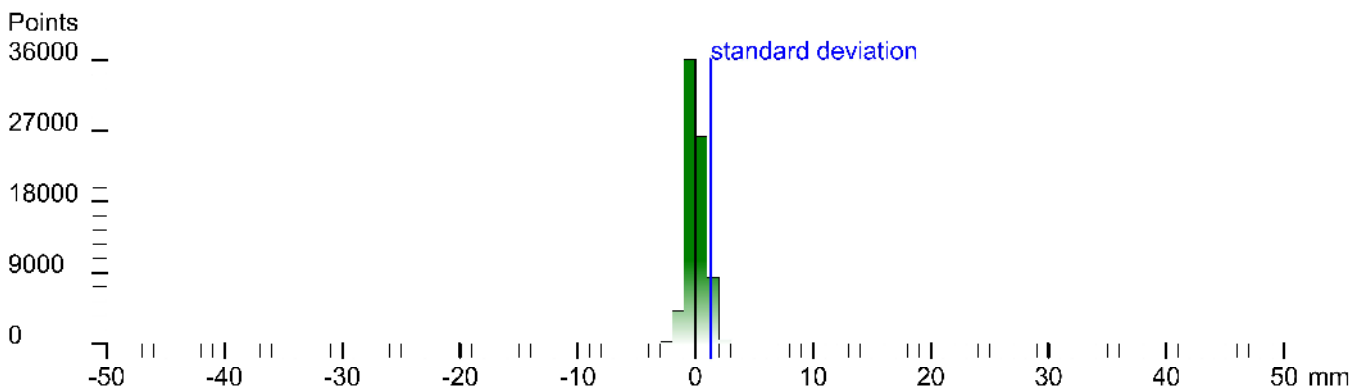
Status registration '[102h] registered with cloud to cloud'

Registration matrix:

```
-0.761987  0.647589  -0.002429  9.8930 m  
-0.647592  -0.761989  0.000215  -6.2314 m  
-0.001712  0.001736  0.999997  2.8917 m  
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation: 1.3 mm

Deviation histogram



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 position: '44' [102h] registered with cloud to cloud  
Sensor  
sensors: 3096 *barome or transition rotation*  
Barometer: 0.777950 bar 2173.96 m  
nav translation: 0.5337 m -8.6172 m 2173.8608 m accuracies: 9.1946 m 9.1945 m 0.0005 m  
nav rotation: 0.0000 0.0000 264.2673 accuracies: 0.0000 0.0000 15.0000  
upside-down: no  
Initial pos position: (0 indoor)  
-3.100 -0.985 0.000 16.474  
0.999 -0.100 0.000 -12.108  
0.000 0.000 1.000 -1.187  
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



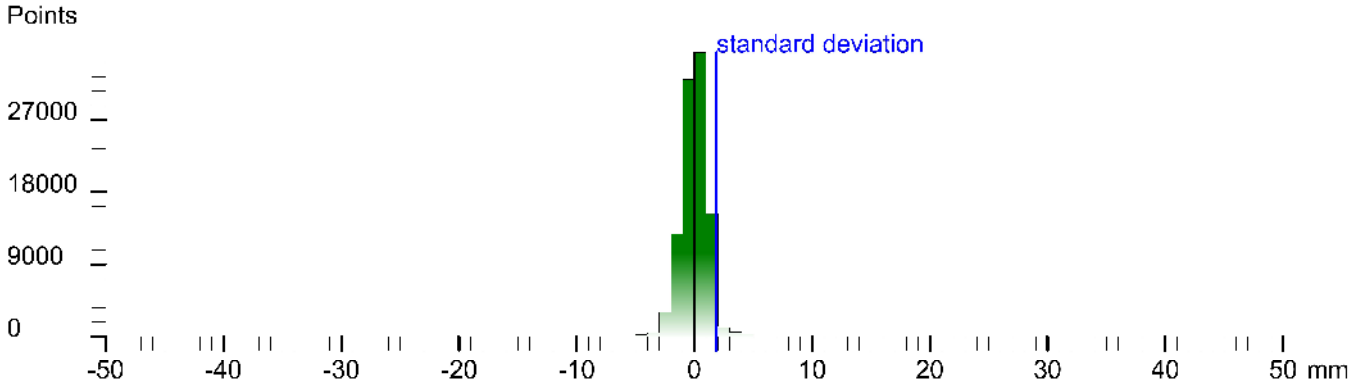
Scan position '45'

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

```
-0.309035 -0.951048 -0.002736 5.4621 m  
0.951051 -0.309037 0.000341 -4.2909 m  
-0.001170 -0.002496 0.999996 2.8631 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 1.9 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: 3096 *barometric transition rotation*
Barometer: 0.778046 bar 2172.37 m
nav translation: 5.4604 m 4.8673 m 2174.5271 m accuracies: 8.7627 m 8.7627 m 0.0000 m
nav rotation: 0.0000 0.0000 -13.3520 accuracies: 0.0000 0.0000 16.0000
upside-down: no
Initial pre position: (Girdoor)
-3.400 0.916 0.000 21.938
-0.916 -0.400 0.000 -7.241
0.000 0.000 1.000 -0.626
0.000 0.000 0.000 1.000

Level system info: dynamic compensator available.



Scan position '46'

Scan position is member of group(s):

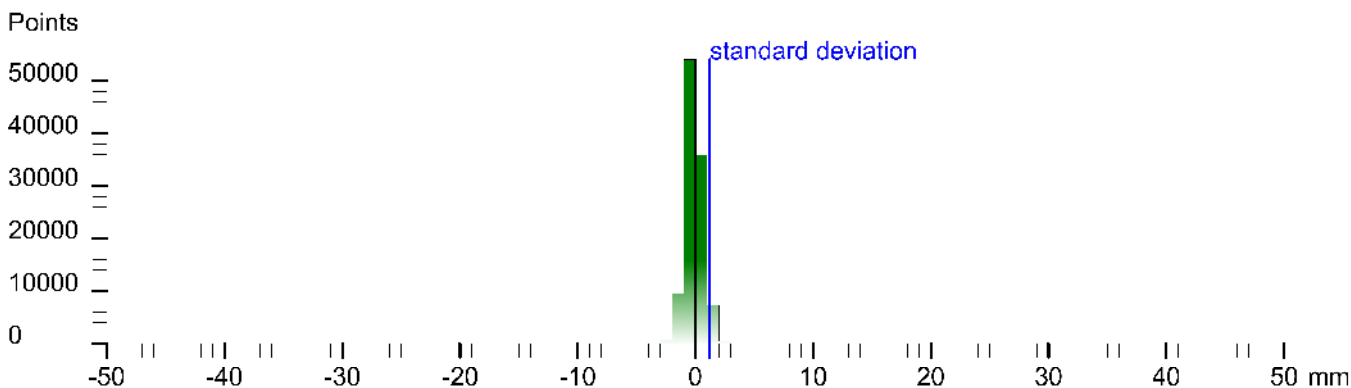
Status registration '[102h] registered with cloud to cloud'

Registration matrix:

```
0.759194 -0.650860 -0.002614 8.4132 m
0.650864 0.759195 0.000678 -2.7935 m
0.001543 -0.002216 0.999996 2.8557 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 1.2 mm

Deviation histogram



Scan '46'

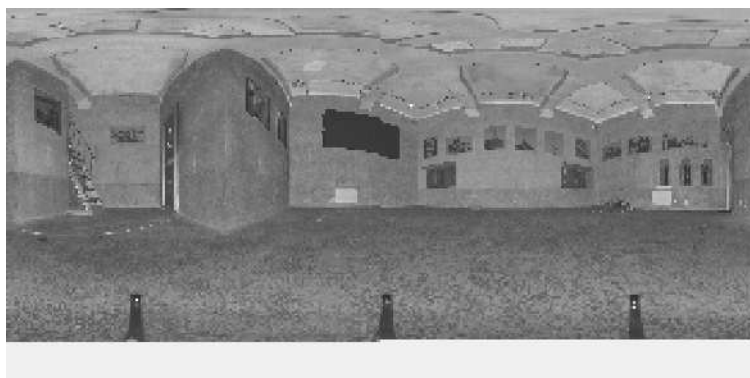
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan position: '46' [102h] registered with cloud to cloud  
Sensor  
sensors: 3096 *barometric transition rotation*  
Barometer: 0.778055 bar 2172.88 m  
nav translation: -3.1080 m -5.7100 m 2173.392 m accuracies: 8.3867 m 8.3867 m 0.0000 m  
nav rotation: 0.0000 0.0000 /3.5412 accuracies: 0.0000 0.0000 15.0000  
up/down: no  
Initial position: (Girdoor)  
0.283 0.958 0.000 18.826  
-0.968 0.283 0.000 -12.941  
0.000 0.000 1.000 -2.014  
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'

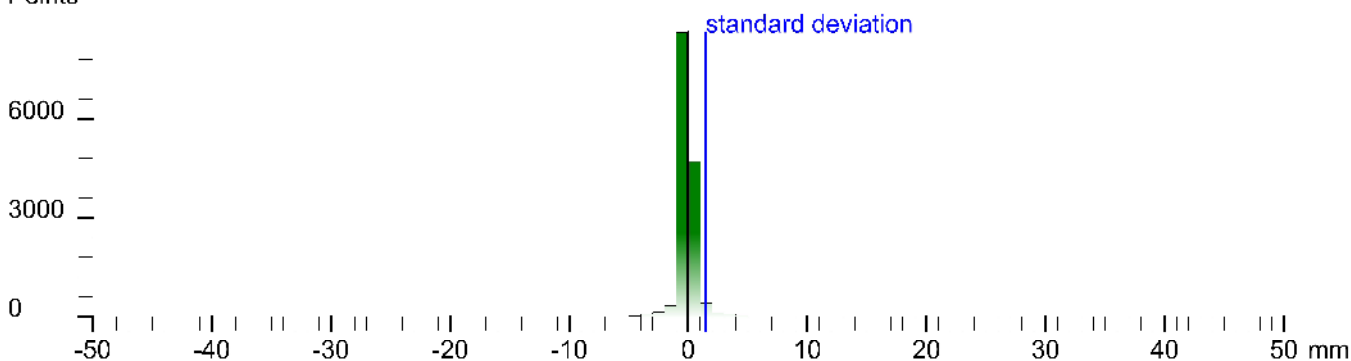
Registration matrix:

```
-0.708051 -0.706163 -0.000156 8.8316 m  
0.706162 -0.708051 0.000455 -0.5095 m  
-0.000432 0.000212 1.000000 4.1729 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 1.5 mm

Deviation histogram

Points



Scan '47'

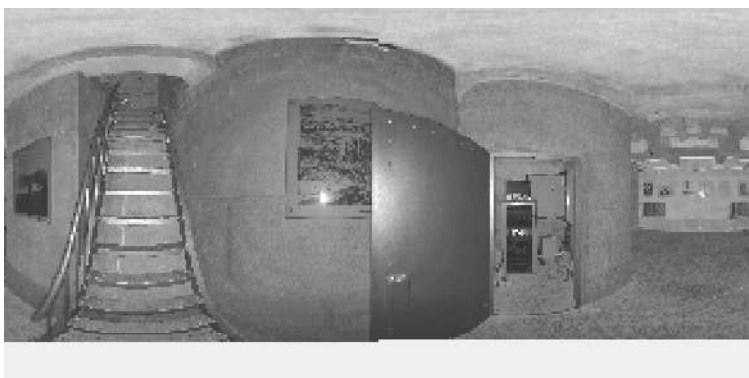
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan position: '47' - name: '47' - number: '47' - group: 'Cloud to Cloud' - status: 'Registered' - registration: 'cloud to cloud' - standard deviation: '1.5' - sensor: 'Z+F IMAGER 5016' - serial number: '5016-0100' - firmware: '9.0.3.6562-0' - scan resolution: 'High' - quality: 'Normal' - up/down: 'no'  
Sensor  
sensors: 3096 *barometric transition rotation*  
Barometer: 0.777805 bar 2175.46 m  
nav translation: -2.3985 m -2.3330 m 2175.1775 m accuracies: 0.0852 m 0.0852 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: (0/door)  
-3.993 -0.117 0.000 16.167  
0.117 -0.993 0.000 -14.984  
0.000 0.000 1.000 0.324  
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '48'

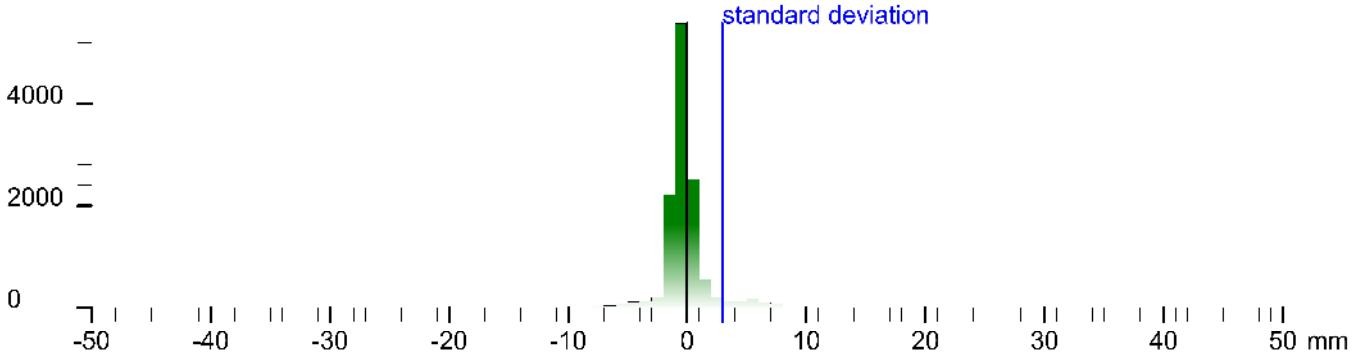
Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```
0.830821  0.556542  0.000703  10.9215 m
-0.556542  0.830820  0.001235  -2.1428 m
0.000103  -0.001418  0.999999  4.1789 m
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation: 2.9 mm

Deviation histogram

Points



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: '48' - name: '48' - number: '48' - type: 'Cloud to Cloud' - status: 'Registered' - registration: 'cloud to cloud' - standard deviation: '2.9' - sensor: 'Z+F IMAGER 5016' - serial number: '5016-0100' - firmware: '9.0.3.6562-0' - scan resolution: 'High' - quality: 'Normal'
Sensor
sensors: 3096 *barometric transition rotation*
Barometer: 0.777868 bar 2176.87 m
nav translation: 2.0159 m 2.224 m 2176.6733 m accuracies: 0.0102 m 0.0102 m 0.0000 m
nav rotation: 0.0000 0.0000 0.0003 / accuracies: 0.0000 0.0000 164.327/s
up/down: no
Initial position (Girdoor)
0.866 0.258 0.000 18.483
-0.268 0.966 0.000 -12.861
0.000 0.000 1.000 1.570
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '49'

Scan position is member of group(s):

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

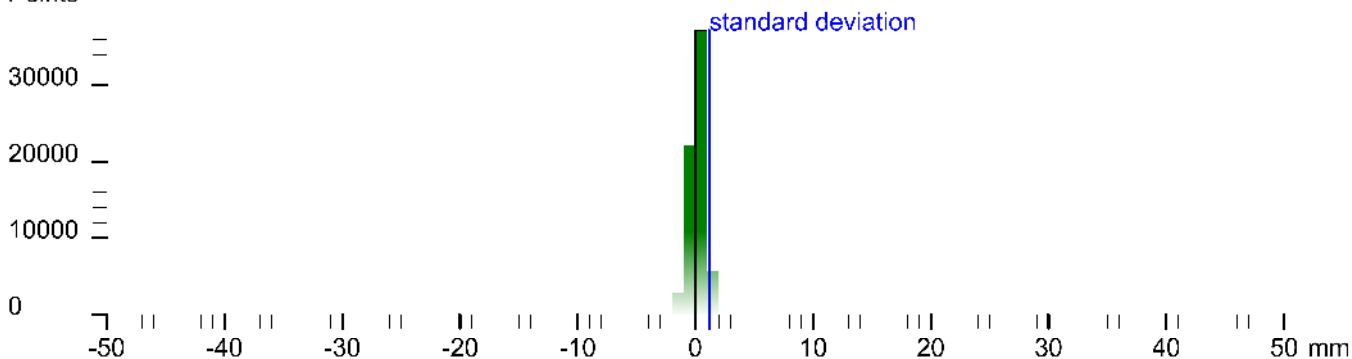
Registration matrix:

```
-0.667524 -0.744588 0.001377 8.4628 m  
0.744589 -0.667521 0.002125 -0.3556 m  
-0.000663 0.002444 0.999997 5.4455 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 1.2 mm

Deviation histogram

Points



Scan '49'

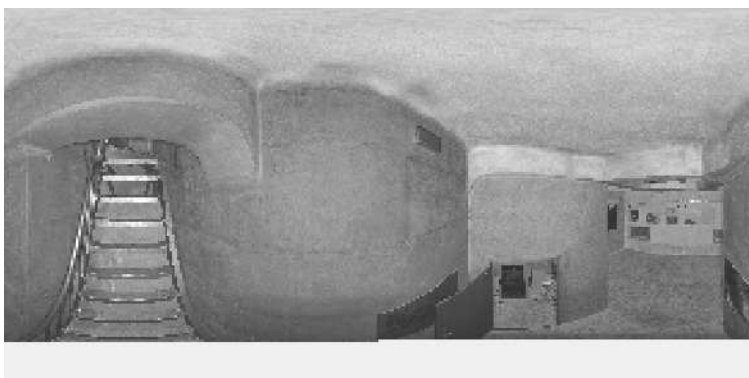
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: null  
Sensor  
sensors: 3096 *barometric transition rotation*  
Barometer: 0.777262 bar 2181.06 m  
nav translation: -1.1983 m 3.7527 m 2180.0696 m accuracies: 7.2734 m 7.2734 m 0.0000 m  
nav rotation: 0.0000 0.0000 238.8633 / accuracies: 0.0000 0.0000 16.0000  
upside-down: no  
Initial pre position (Girdoor)  
-3.878 -0.178 0.000 11.315  
0.478 -0.878 0.000 -12.109  
0.000 0.000 1.000 4.976  
0.000 0.000 0.000 1.000
```

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



Scan position '5'

Scan position is member of group(s):

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

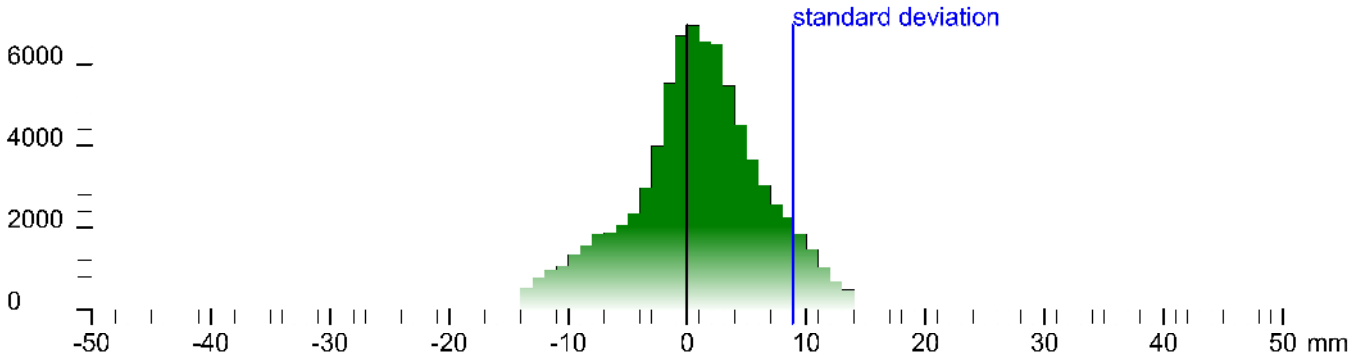
Registration matrix:

```
0.966467 -0.256791 -0.000221 4.9981 m
0.256791 0.966467 -0.000696 -3.6032 m
0.000392 0.000616 1.000000 8.2800 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:8.8 mm

Deviation histogram

Points



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
Sensor
sensors: 3100 *barome or transition rotation gps
Barometer: 0.777864 bar 2176.3° m
nav translation: -3.9686 m 3.8913 m 2178.6802 m accuracies: 5.7779 m 5.7779 m 0.0000 m
nav rotation: 0.0000 0.0000 290.4846 accuracies: 0.0000 0.0000 16.0000
upside-down: no
GPS lat:45.15989 long:25.497513 satellites:6 height:2337.0 m hdop:1.6 vdop:1.7 m hacc:6.0m vacc:6.8 flags:G3 's are above 3D solution'
north:5030261.121 m east:382411.216 m zone:35T
Initial pre position (3-coo. tooor):
0.350 -0.937 0.000 -1.680
0.937 0.350 0.000 1.650
0.000 0.000 1.000 3.627
0.000 0.000 0.000 1.000
```

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



Scan position '50'

Scan position is member of group(s):

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

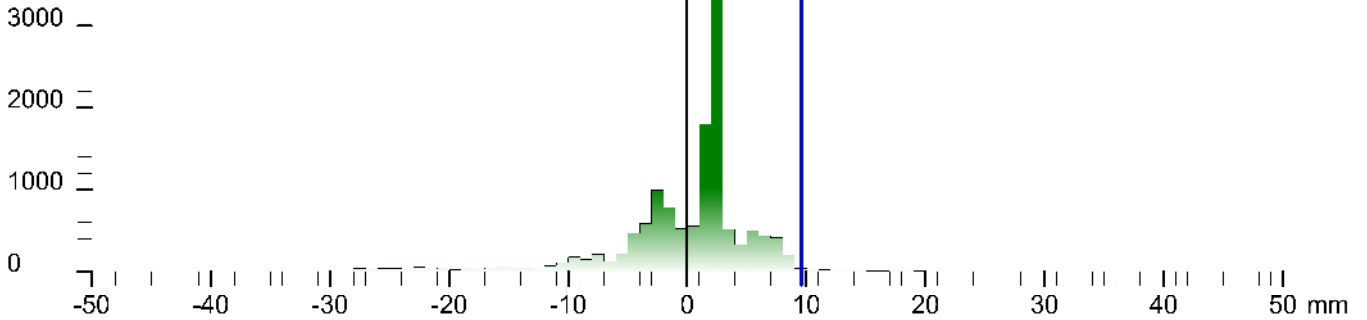
Registration matrix:

```
-0.279852  0.960041  -0.002585  5.8655 m
-0.960044  -0.279850  0.000807  -1.6740 m
0.000052  0.002707  0.999996  4.1476 m
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation: 9.6 mm

Deviation histogram

Points



Scan '50'

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 *barometer transition rotation*

Barometer: 0.777238 bar 2181.3 m
nav translation: -1.6977 m -1.5217 m 2171.7163 m accuracies: 0.0038 m 0.0038 m 0.0177 m
nav rotation: 0.0000 0.0000 263.487° accuracies: 0.0000 0.0000 1s.0000
up/down: no

Initial pos position (Girdoor)
-3.113 -0.894 0.000 12.050
0.994 -0.113 0.000 -13.637
0.000 0.000 1.000 -3.437
0.000 0.000 0.000 1.000

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



Scan position '51'

Scan position is member of group(s):

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

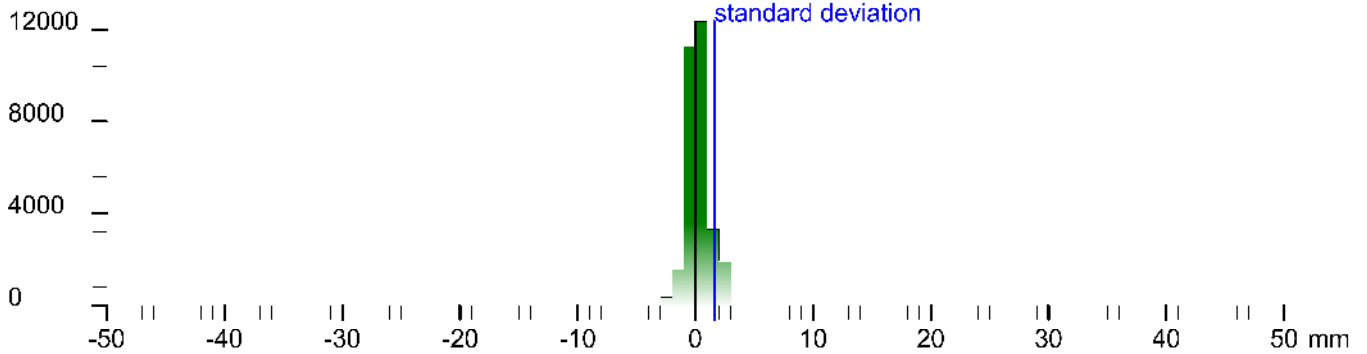
Registration matrix:

```
-0.914437  0.404730 -0.000487  6.6852 m  
-0.404730 -0.914437  0.000452  0.0194 m  
-0.000262  0.000610  1.000000  3.8713 m  
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation: 1.6 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: full 1.9420x3.8713 m (angle: 1.48:51) scanner: Z+F Imager 5016 serial number: 5016-0100 firmware: 9.0.3.6562-0  
Sensor  
sensors: 3096 *barometric transition rotation*  
Barometer: 0.777402 bar 2179.6 m  
nav translation: 1.9420 m 0.9819 m 2180.0590 m accuracies: 0.1985 m 0.1985 m 0.0000 m  
nav rotation: 0.0000 0.0000 269.0062 accuracies: 0.0000 0.0000 1s.0000  
upside-down: no  
Initial pos position: (0 indoor)  
-3.087 -0.986 0.000 11.592  
0.996 -0.087 0.000 -12.646  
0.000 0.000 1.000 4.9e-6  
0.000 0.000 0.000 1.000
```

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



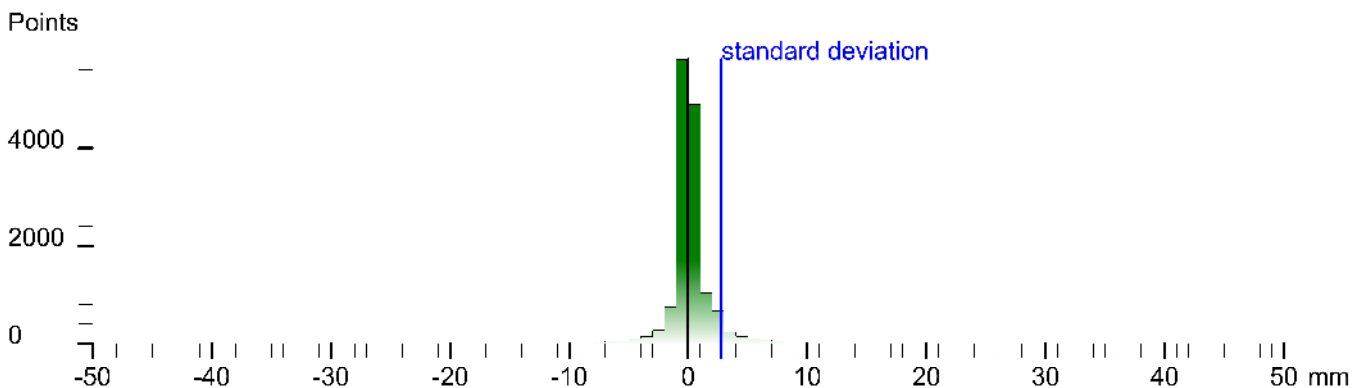
Scan position '52'

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

```
0.616542 -0.787323 -0.000068 7.2218 m  
0.787323 0.616541 0.001041 -0.5346 m  
-0.000778 -0.000695 0.999999 2.8678 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:2.8 mm

Deviation histogram



Scan '52'

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: 0.777770 bar 2175.82 m  
nav translation: -3.9085 m 3.0415 m 2175.4883 m accuracies: 5.0049 m 5.0049 m 0.0007 m  
nav rotation: 0.0000 0.0000 25.3670 accuracies: 0.0000 0.0000 15.0000  
upside-down: no  
Initial pos position (Girdoor)  
0.801 0.428 0.000 13.621  
-0.428 0.904 0.000 -12.604  
0.000 0.000 1.000 0.335  
0.000 0.000 0.000 1.000
```

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



Scan position '53'

Scan position is member of group(s):

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

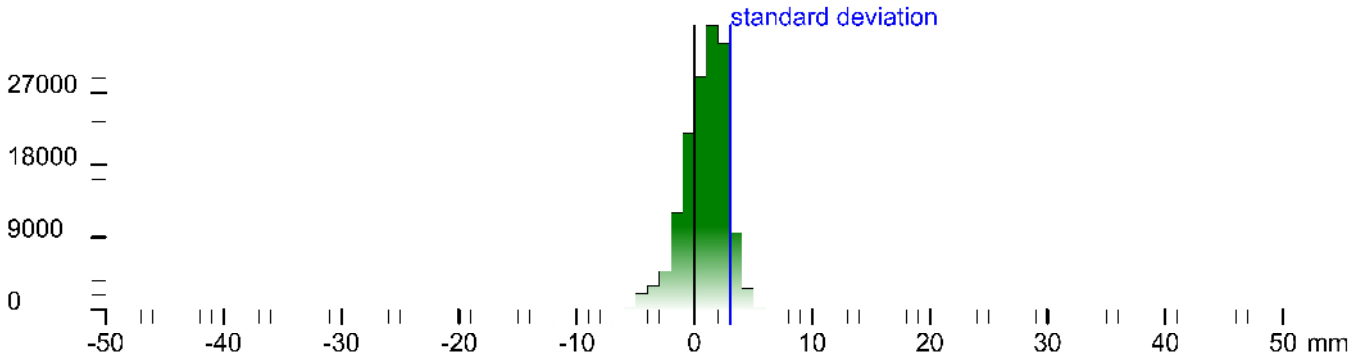
Registration matrix:

```
-0.212385 -0.977186 -0.000334 2.3506 m  
0.977186 -0.212386 0.000527 7.4670 m  
-0.000586 -0.000215 1.000000 -0.2660 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:3.1 mm

Deviation histogram

Points



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 comment: full 100% scan of a building facade  
Sensor  
sensors: 3100 *barometer transition rotation gps  
Barometer: 0.776517 bar 2188.75 m  
nav translation: 0.0000 m 0.0000 m 2189.0° 90 m accuracies: 5.1000 m 5.1000 m 0.0000 m  
nav rotation: 0.0000 0.0000 261.7422 accuracies: 0.0000 0.0000 1s.0000  
upside-down: no  
GPS lat:45.16081 long:25.497406 satellites:6 height:2326.1 m hdop:1.1 vdoop:1.8 m hacc:4.7 m vacc:6.1 flags:G3 's are above 3D solution'  
north:5030268.329 m east:382433.008 m zone:35T  
Initial pre position (3-coor):  
-0.313 -0.850 0.000 -9.883  
0.950 -0.313 0.000 9.205  
0.000 0.000 1.000 13.566  
0.000 0.000 0.000 1.000
```

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



Scan position '54'

Scan position is member of group(s):

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

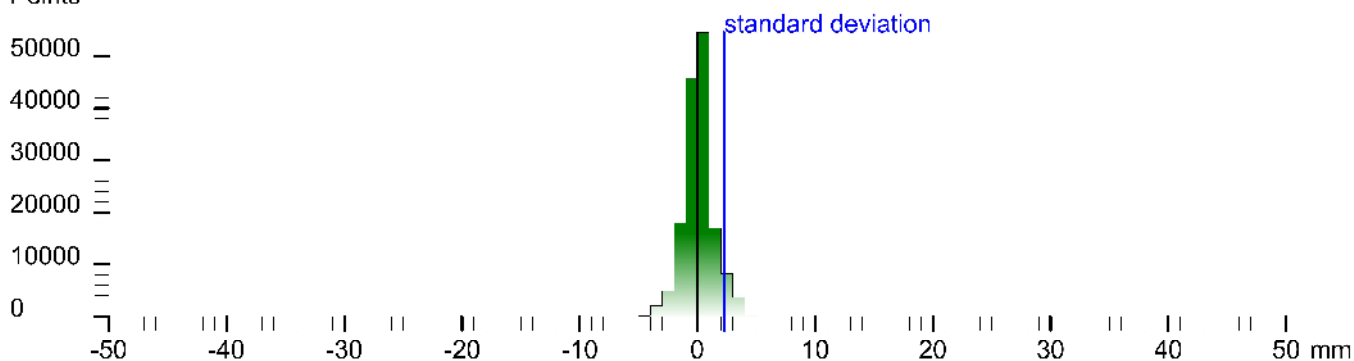
Registration matrix:

```
0.778903 -0.627145 -0.000427 10.4215 m
0.627145 0.778903 0.000466 6.3941 m
0.000040 -0.000631 1.000000 -0.2721 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:2.3 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 name: full_190804_1037 - name: 146-154 - name: 54 - path: C:\Users\Edin\Desktop\54 - scan name: C:\Users\Edin\Desktop\54 - scan type: Range - type: active - stamp: 20190804_1037 - scan: Scan - scan type: active - scan: 146-154 - scan: 54 - scan: 54  
Sensor  
sensors: 3100 *barometer transition rotation gps  
Barometer: 0.776569 bar 2188.2 m  
nav translation: 1.5186 m 7.3370 m 2188.1611 m accuracies: 8.8588 m 8.8588 m 0.0005 m  
nav rotation: 0.0000 0.0000 288.8666 accuracies: 0.0000 0.0000 18.0000  
upside-down: no  
GPS: lat:45.16115 long:25.497507 satellites:8 height:2327.8m hdop:1.3 vdop:1.7m hdacc:4.7m vhdacc:4.7m tags:G3 'stand alone 3D solution'  
north:5030275.114 nr east:382411.028 m zone:35T  
Initial pre position (3co. tocoor)  
0.318 -0.948 0.000 -1.888  
0.948 0.318 0.000 15.058  
0.000 0.000 1.000 13.038  
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:

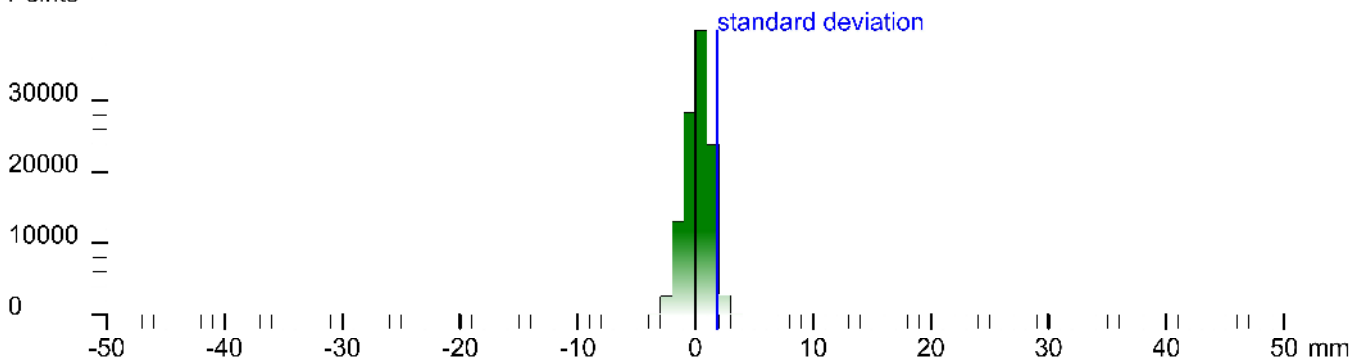
```

0.985898 -0.167351 0.000085 18.9986 m
0.167351 0.985898 0.000394 2.6215 m
-0.000150 -0.000374 1.000000 -0.2522 m
0.000000 0.000000 0.000000 1.0000
    
```

Result registration cloud to cloud standard deviation: 1.8 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: 45.16090 lon: 25.497623 satellites: 8 height: 2326.4 m hdop: 1.2 vdoor: 1.8 m hacc: 4.9 m vacc: 4.6 flags: G3 's' are: sbno 3D solution'

Sensor
 sensors: 3100 *barome or transtion rotation gps
 Barometer: 0.776561 bar 2188.29 m
 nav translation: 1.1 329 m 9.8119 m 2187.5 15 m accuracies: 10.0636 m 10.0636 m 0.0000 m
 nav rotation: 0.0000 0.0000 0.0000 0.1117/2/2 accuracies: 0.0000 0.0000 18.0000
 upside-down: no
 GPS lat: 45.16090 lon: 25.497623 satellites: 8 height: 2326.4 m hdop: 1.2 vdoor: 1.8 m hacc: 4.9 m vacc: 4.6 flags: G3 's' are: sbno 3D solution'

Initial pre position (3-coo. tooor)
 0.686 -0.7 -6 0.000 7.135
 0.748 0.886 0.000 10.990
 0.000 0.000 1.000 12.358
 0.000 0.000 0.000 1.000

Level system info: dynamic compensator available.



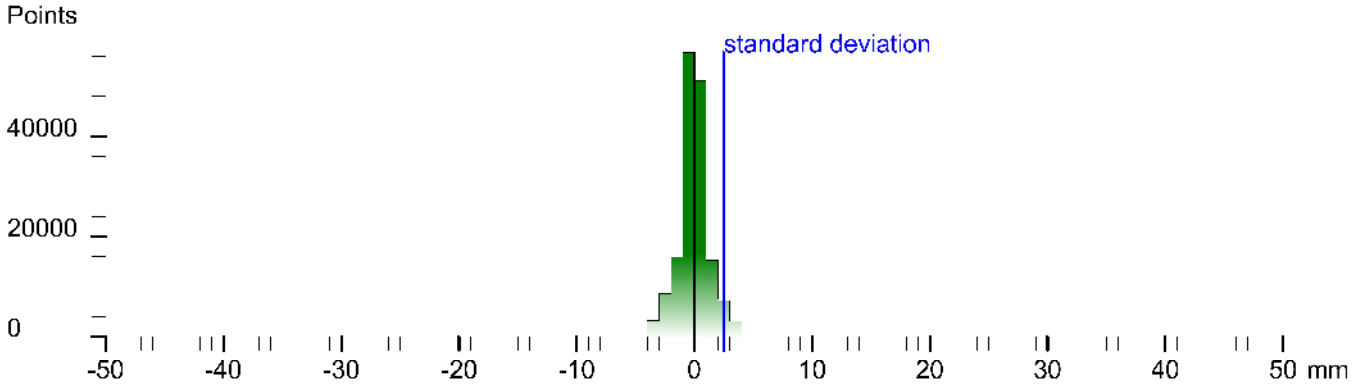
Scan position '56'

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

```
-0.643774  0.765217 -0.000278 17.5230 m
-0.765217 -0.643774  0.000211 -4.4381 m
-0.000018  0.000349  1.000000 -0.2479 m
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation:2.5 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:
Sensor:
sensors: 3100 *barometer, transition, rotation, gps
Barometer: 0.776564 bar 2188.26 m
nav translation: 5.4718 m -6.6988 m 2187.3230 m accuracies: 9.1502 m 9.1502 m 0.0007 m
nav rotation: 0.0000 0.0000 76.0949 accuracies: 0.0000 0.0000 1s,0.000
upside-down: no
GPS lat:45.16091 long:25.497622 satellites:8 height:2327.7 m hdop:1.0 vdoop:1.7 m hacc:3.5m vacc:4.7 flags:G3 's:anc:slbnr 3D solution'
north:5030265.623 m east:382419.809 m zone:35T
Initial pre position (3-coor):
0.740 0.971 0.000 6.955
-0.971 0.240 0.000 6.556
0.000 0.000 1.000 12.670
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



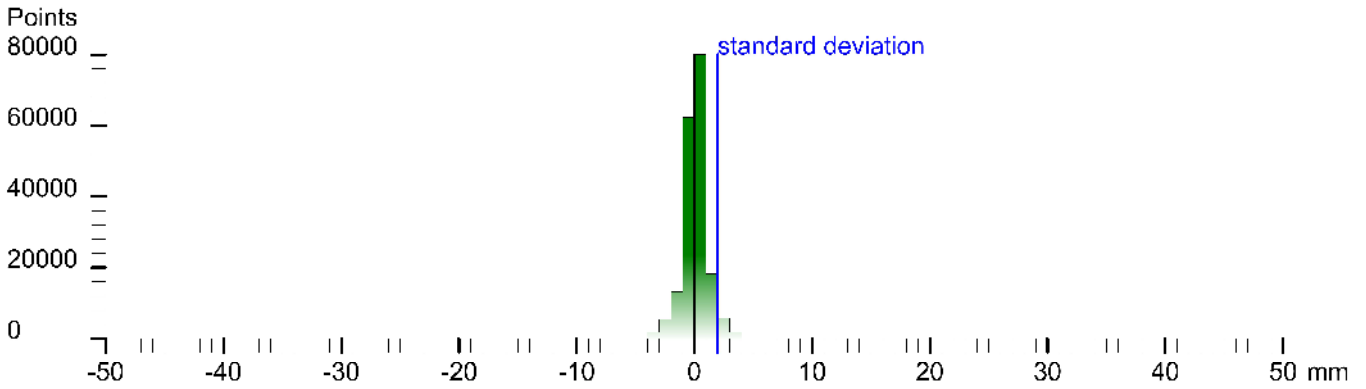
Scan position '57'

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

```
-0.925025 0.379907 -0.000145 16.1542 m  
-0.379907 -0.925025 0.000082 -7.9803 m  
-0.000103 0.000131 1.000000 -0.2369 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:2.0 mm

Deviation histogram



Scan '57'

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: 145.16004 long 25.497606 latitude 2325.3 height 2.0 vdoor 2.9 m hacc 5.0 m vacc 6.4 flags G3 's' arri sbrn 3D solution'
Initial pre position (3-coo, tocoo):
-0.230 0.973 0.000 5.647
-0.973 -0.230 0.000 2.580
0.000 0.000 1.000 12.239
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:

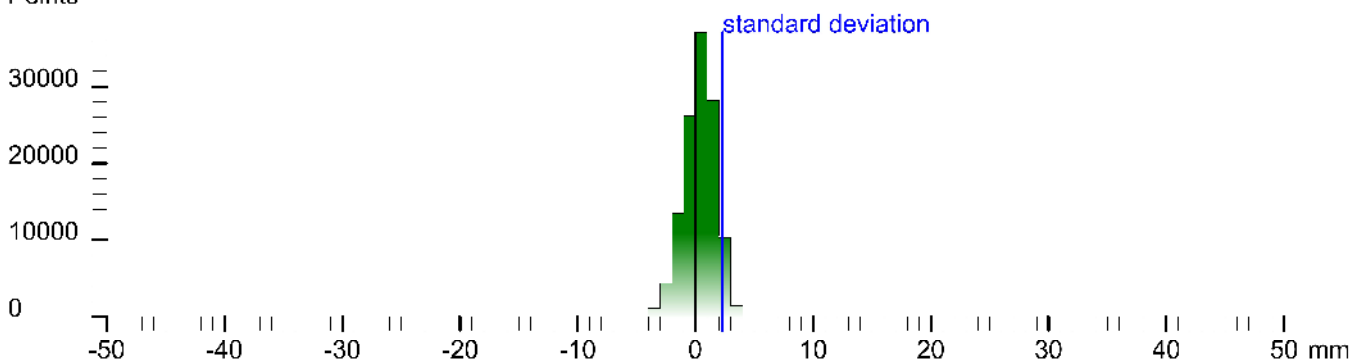
```

0.277859  0.960622  -0.000160  13.5724 m
-0.960622  0.277859  0.000037  -14.3124 m
0.000080  0.000143  1.000000  -0.2290 m
0.000000  0.000000  0.000000  1.0000
    
```

Result registration cloud to cloud standard deviation: 2.3 mm

Deviation histogram

Points



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

```

Scan position: '58' - name: '58' - type: 'Point Cloud' - status: 'Registered' - registration: 'Cloud to Cloud' - standard deviation: '2.3 mm' - quality: 'High' - resolution: 'Normal'
Sensor
sensors: 3100 * barometer/transition rotation/gps
Barometer: 0.776884 bar 2186.92 m
nav translation: -5.2738 m -1.5524 m 2187.0396 m accuracies: 7.8701 m 7.8701 m 0.0000 m
nav rotation: 0.0000 0.0000 0.0000 59.1309 accuracies: 0.0000 0.0000 0.0000
upside-down: no
GPS lat: 45.15943 long: 25.497623 satellites: 8 height: 2326.5 m hdop: 1.1 vdoop: 1.8 m hacc: 3.5 m vacc: 5.0 flags: G3 's' ari aribo 3D solution'
north: 5030266.873 m east: 382419.777 m zone: 35T
Initial pre position (3-coor):
0.776 0.331 0.000 6.851
-0.631 0.776 0.000 -4.221
0.000 0.000 1.000 11.586
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'

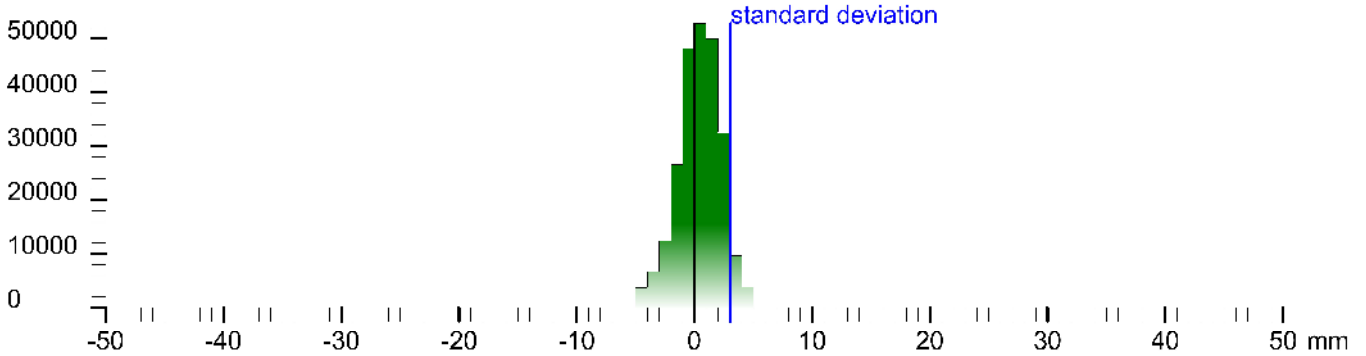
Registration matrix:

```
-0.927498  0.373830 -0.000208  5.5187 m  
-0.373829 -0.927498 -0.000220 -11.9301 m  
-0.000275 -0.000126  1.000000  0.2376 m  
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation: 3.1 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  
Sensor  
sensors: 3100 *barome or transition rotation gps  
Barometer: 0.776815 bar 2187.74 m  
nav translation: 1.8132 m -2.590° m 2186.5132 m accuracies: 0.0834 m 0.0834 m 0.0006 m  
nav rotation: 0.0000 0.0000 ° 53.2038 accuracies: 0.0000 0.0000 15.0000  
upside-down: no  
GPS lat:45.15024 long:25.497524 satellites:8 height:233° 0m hdop:1.0 vdop:1.9m hacc:2.8m vacc:6.0 flags:G3 's'anc sbnc 3D solution'  
north:5030263.899 m east:382411.977 m zone:35T  
Initial pre position (3-co. tocoor)  
-0.893 0.451 0.000 -0.934  
-0.451 -0.083 0.000 -8.108  
0.000 0.000 1.000 11.366  
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:

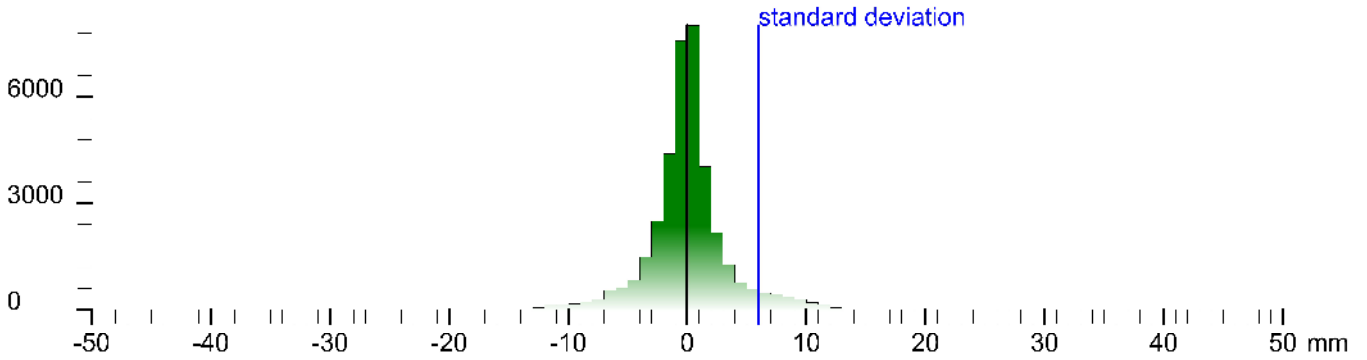
```

0.721954  0.691942  0.000037  6.4926 m
-0.691941  0.721954  0.000743  -2.4147 m
0.000487  -0.000562  1.000000  8.2308 m
0.000000  0.000000  0.000000  1.0000
    
```

Result registration cloud to cloud standard deviation:6.0 mm

Deviation histogram

Points



Scan '6'

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

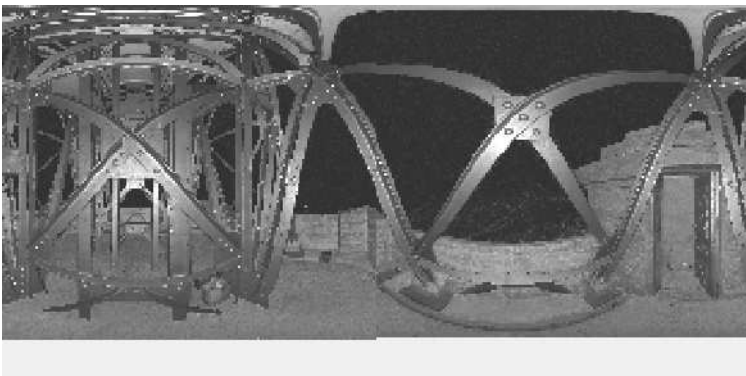
Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```

Sensor
sensors: 3100 *barometric transition rotation gps
Barometer: 0.777710 bar 2176.43 m
nav translation: 0.3622 m 0.4208 m 2176.3672 m accuracies: 5.9801 m 5.9801 m 0.0000 m
nav rotation: 0.0000 0.0000 *57.9374 accuracies: 0.0000 0.0000 1s.0000
upside-down: no
GPS lat:45.16004 long:25.497498 satellites:6 height:2339.4m hdop:1.0 vdoop:1.7m hacc:8.5m vacc:8.0 flags:G3 's are able 3D solution'
north:5030262.838 m east:382410.057 m zone:35T
Initial pre position (3.o.tccor):
-0.742 0.670 0.000 -2.803
-0.670 -0.742 0.000 2.730
0.000 0.000 1.000 1.274
0.000 0.000 0.000 1.000
    
```

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



Scan position '60'

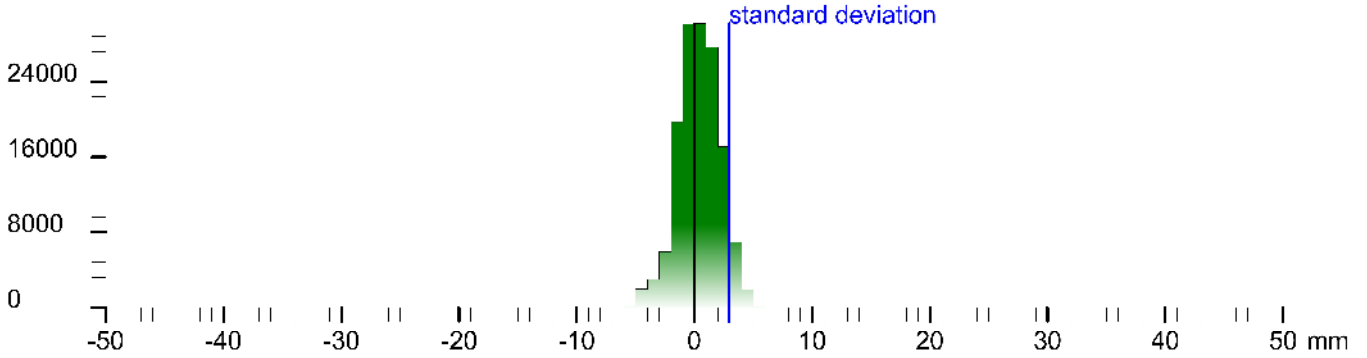
Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```
0.128000 -0.991774 -0.000322 -2.9517 m
0.991775 0.127999 0.000295 -8.5469 m
-0.000251 -0.000357 1.000000 -0.0997 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:2.9 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 position: '60' - name: '148:60' - status: 'OK' - type: 'Cloud to Cloud' - registration: 'Cloud to Cloud' - registration matrix: '0.128000 -0.991774 -0.000322 -2.9517 m
0.991775 0.127999 0.000295 -8.5469 m
-0.000251 -0.000357 1.000000 -0.0997 m
0.000000 0.000000 0.000000 1.0000'
Sensor:
sensors: 3100 * barometer transition rotation gps
Barometer: 0.776761 bar 2186.23 m
nav translation: 0.0000 m 0.0000 m 2186.2092 m accuracies: 5.1366 m 5.1366 m 0.0000 m
nav rotation: 0.0000 0.0000 0.0000 232.6244 accuracies: 0.0000 0.0000 16.0000
upside-down: no
GPS lat:45.15026 long:25.497412 satellites:5 height:233.13 m hdop:1.6 vdop:6.3 m hacc:4.2m vacc:10.0 tags:G3 'stand alone 3D solution'
Initial pre position (3-coo. tocoor):
-0.608 -0.794 0.000 -9.688
0.794 -0.808 0.000 -5.579
0.000 0.000 1.000 11.356
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '61'

Scan position is member of group(s):

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

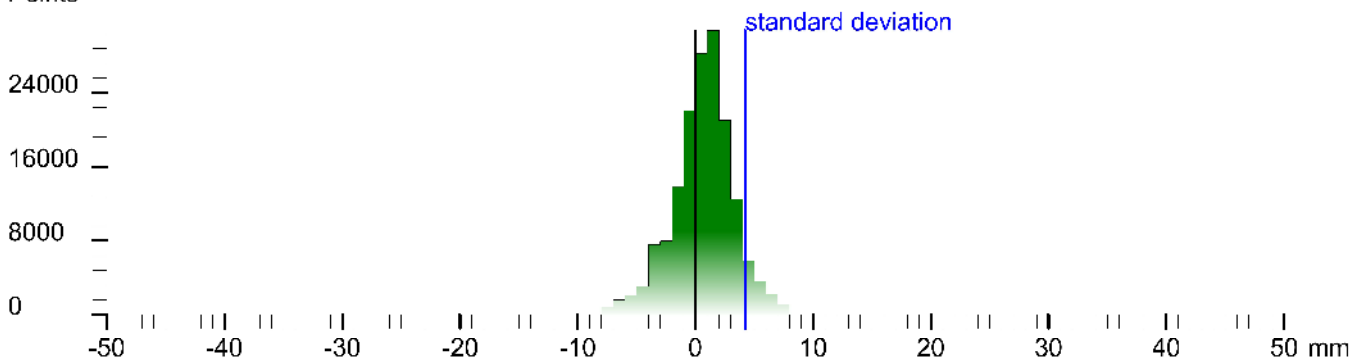
Registration matrix:

```
-0.968296  0.249806  -0.000665  -6.7043 m
-0.249806  -0.968297  0.000423  -4.0232 m
-0.000538  0.000576   1.000000  -1.8036 m
0.000000   0.000000   0.000000   1.0000
```

Result registration cloud to cloud standard deviation:4.2 mm

Deviation histogram

Points



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

```
Scan position: '61' [102h] registered with cloud to cloud
Sensor
sensors: 3100 *barometric transition rotation gps
Barometer: 0.776029 bar 2184.49 m
nav translation: -3.4071 m -27.1410 m 2 *83.6208 m accuracies: 1 5.3136 m 18 3136 m 0.0006 m
nav rotation: 0.0000 0.0000 68.8888 * accuracies: 0.0000 0.0000 15.0000
upside-down: no
GPS lat:45.15047 long:25.497340 satellites:6 height:2326.6 m hdop:1.6 vdoor: 1.6 m hacc:5.5m vacc:5.5 flags:G3 's:anc:abno 3D solution'
north:5030266.699 m east:382428.295 m zone:35T
Initial pre position (3-coo. tocoor)
0.380 0.933 0.000 -4.578
-0.933 0.380 0.000 -3.377
0.000 0.000 1.000 8.468
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '62'

Scan position is member of group(s):

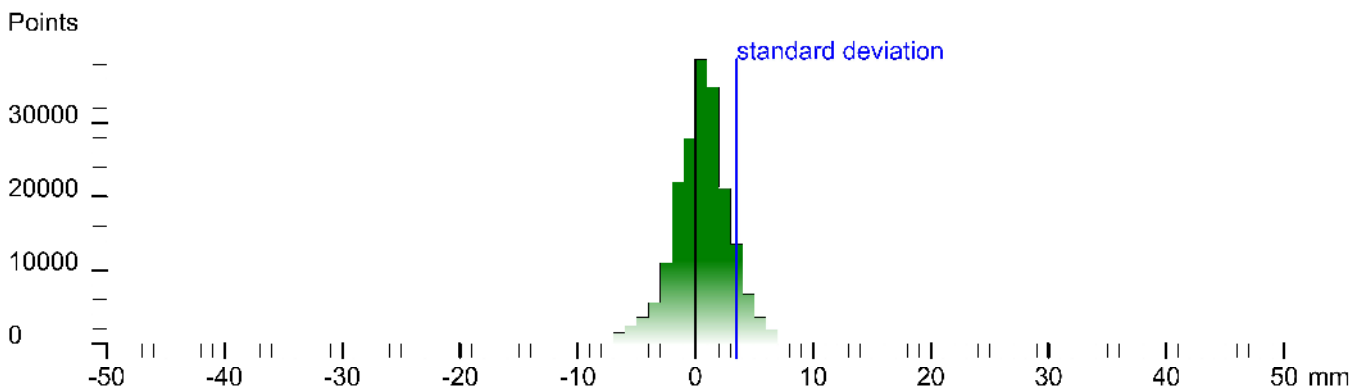
Status registration '[102h] registered with cloud to cloud'

Registration matrix:

```
-0.984171 0.177221 -0.000695 -3.6729 m
-0.177221 -0.984172 0.000060 5.2194 m
-0.000673 0.000182 1.000000 -1.8044 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:3.5 mm

Deviation histogram



Scan '62'

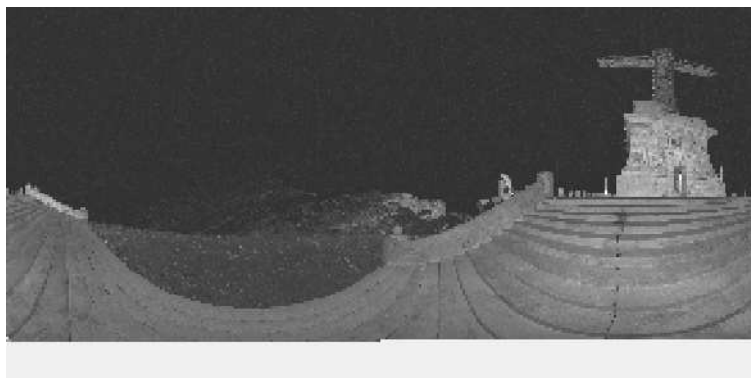
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: null  
Sensor  
sensors: 3100 *barome or transition rotation gps  
Barometer: 0.776912 bar 2184.67 m  
nav translation: 1.7402 m -0.8907 m 2184.3367 m accuracies: 5.8153 m 5.8153 m 0.0005 m  
nav rotation: 0.0000 0.0000 * 98.8976 accuracies: 0.0000 0.0000 1s:0.0000  
upside-down: no  
GPS lat:145.16019 long:25.497328 satellites:8 height:2326.6 m hdop:1.0 vdoor: 1.6 m hacc:2.4m vacc:3.6 flags:G3 's.anc. sbrn 3D solution'  
north:5030264.781 m east:382426.803 m zone:35T  
Initial pre position (3-coo. tocoor):  
-0.989 -0.15 0.000 -16.073  
0.51 -0.989 0.000 4.653  
0.000 0.000 1.000 9.152  
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '63'

Scan position is member of group(s):

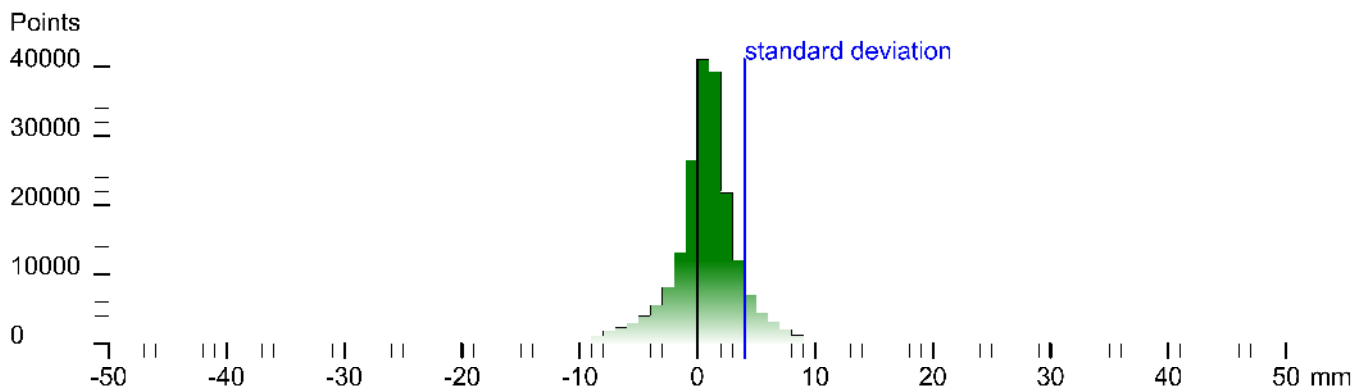
Status registration '[102h] registered with cloud to cloud'

Registration matrix:

```
-0.968717  0.248164  -0.001798  -13.1706 m  
-0.248165  -0.968718  0.000552   0.3912 m  
-0.001605  0.000981  0.999998  -3.6542 m  
0.000000  0.000000  0.000000   1.0000
```

Result registration cloud to cloud standard deviation:4.0 mm

Deviation histogram



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

```
Scan position: '63' - name: '63' - x: 148.763 - y: 95.945 - z: 2327.2 - height: 1.2 - vdoor: 1.7 - hacc: 4.4 - vacc: 5.6 - flags: G3 's: none - 3D solution'  
Sensor  
sensors: 3100 * barome or transition rotation gps  
Barometer: 0.777055 bar 2183.19 m  
nav translation: -11.5862 m 7.7748 m 2.927551 m accuracies: 12.0626 m 12.0626 m 0.0000 m  
nav rotation: 0.0000 0.0000 -56.3372 accuracies: 0.0000 0.0000 15.0000  
upside-down: no  
GPS lat: 45.15070 long: 25.497250 satellites: 7 height: 2327.2 m hdop: 1.2 vdoor: 1.7 m hacc: 4.4 m vacc: 5.6 flags: G3 's: none - 3D solution'  
north: 5030258.386 m east: 382420.582 m zone: 35T  
Initial pre position (3-coor):  
-0.7773 0.890 0.000 -22.277  
-0.600 -0.723 0.000 -0.677  
0.000 0.000 1.000 7.602  
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:

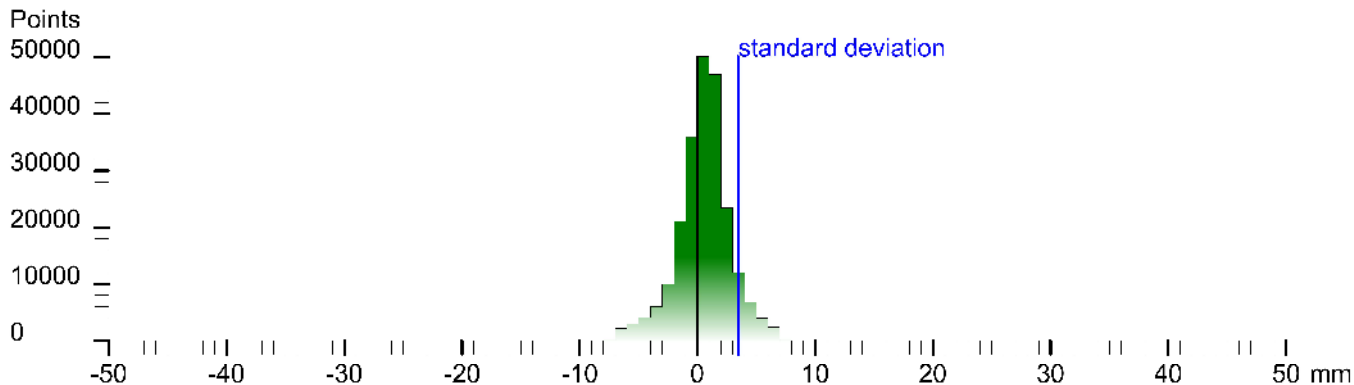
```

-0.998432 0.055993 -0.000528 -10.1409 m
-0.055993 -0.998432 0.000178 8.7527 m
-0.000518 0.000207 1.000000 -3.5351 m
0.000000 0.000000 0.000000 1.0000

```

Result registration cloud to cloud standard deviation:3.5 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	

```

Sensor
sensors: 3100 *barome or transtion rotation gps
Barometer: 0.777055 bar 2183.19 m
nav translation: 8.9632 m -2.8952 m 2183.0159 m accuracies: 9.8973 m 9.8973 m 0.0000 m
nav rotation: 0.0000 0.0000 *60.6770 accuracies: 0.0000 0.0000 15.0000
upside-down: no
GPS lat:45.16091 long:25.497246 satellites:8 height:2327.4 m hdop:1.0 vdoor:1.7 m hacc:3.4m vacc:4.4 flags:G3 's are able 3D solution'
north:5030266.173 m east:382423.410 m zero:35T
Initial pre position (3-coo. tocoor)
-0.944 0.331 0.000 -22.464
-0.331 -0.944 0.000 6.108
0.000 0.000 1.000 7.863
0.000 0.000 0.000 1.000

```

Level system info: dynamic compensator available.



Scan position '65'

Scan position is member of group(s):

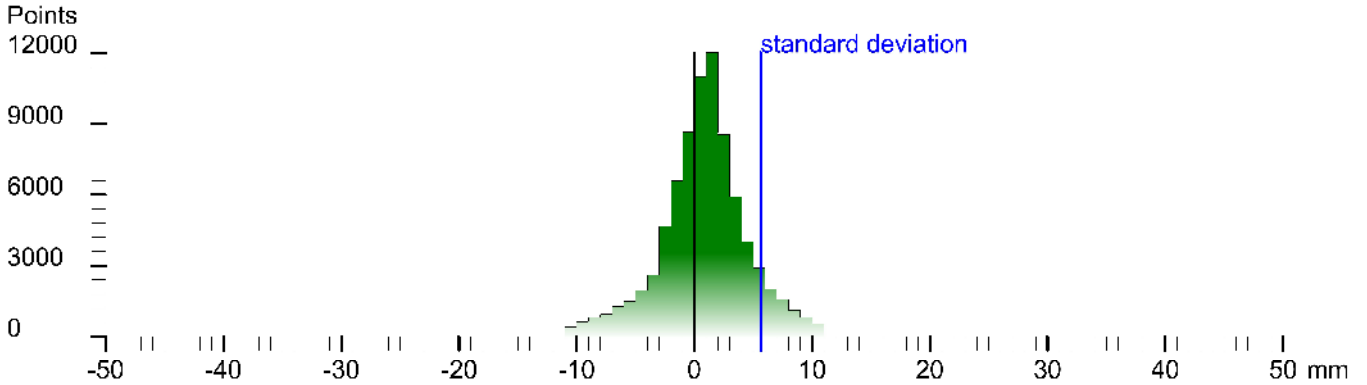
Status registration '[102h] registered with cloud to cloud'

Registration matrix:

```
-0.910853  0.412733 -0.000315 -20.6505 m
-0.412733 -0.910853  0.000137  2.2365 m
-0.000230  0.000255  1.000000 -6.5032 m
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation:5.6 mm

Deviation histogram



Scan '65'

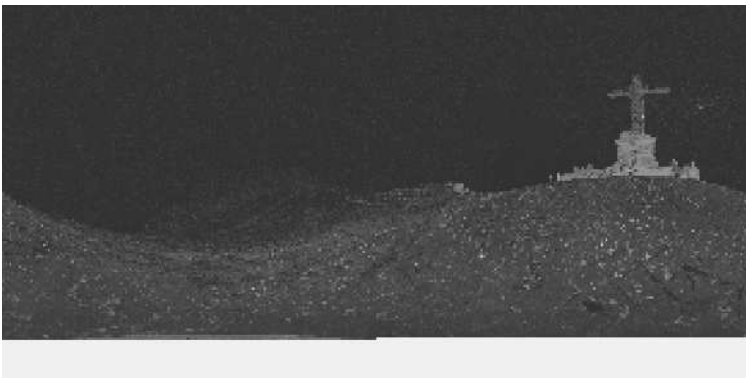
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata Value
comment
operator

```
Scan position: '65' - name: '65' - type: 'Cloud to Cloud' - status: 'Registered' - registration matrix: '-0.910853  0.412733 -0.000315 -20.6505 m
0.412733 -0.910853  0.000137  2.2365 m
-0.000230  0.000255  1.000000 -6.5032 m
0.000000  0.000000  0.000000  1.0000'
Sensor
sensors: 3100 * barometer transition rotation gps
Barometer: 0.777352 bar 2180.13 m
nav translation: 6.6771 m -11.7518 m 2.903921 m accuracies: 12.0026 m 12.0026 m 0.0005 m
nav rotation: 0.0000 0.0000 -26.2867 accuracies: 0.0000 0.0000 15.0000
upside-down: no
GPS lat:45.15951 long:25.497141 satellites:6 height:2316.8 m hdop:1.4 vdoop:2.2 m hacc:4.5 m vacc:5.4 flags:G3 's:smc:smc 3D solution'
north:5030267.26 m east:3824.2036 m zero:35T
Initial pre position (3-coor):
-0.6290 0.785 0.000 -30.845
-0.705 -0.620 0.000 -2.628
0.000 0.000 1.000 5.239
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'

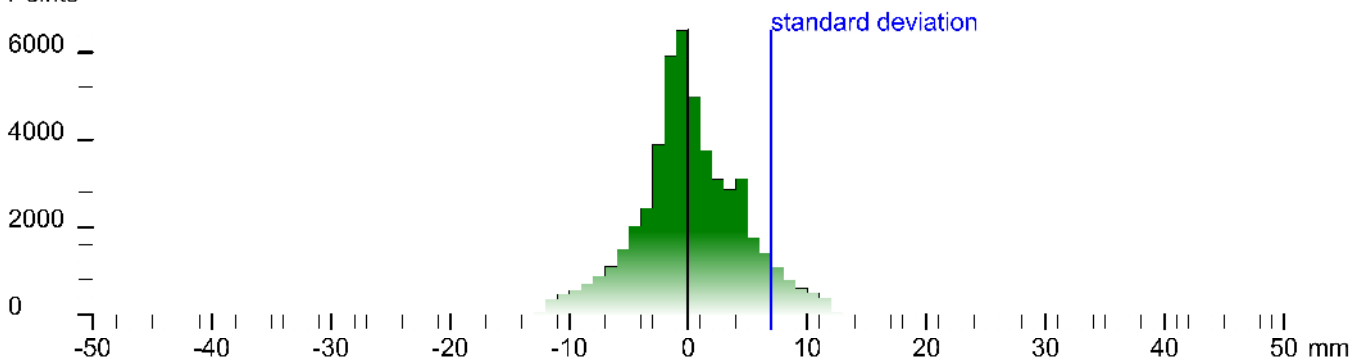
Registration matrix:

```
0.960192 -0.279343 -0.000898 -13.0148 m
0.279343 0.960192 0.000087 -10.2710 m
0.000838 -0.000334 1.000000 -4.6394 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:6.9 mm

Deviation histogram

Points



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 position: '66' [102h] registered with cloud to cloud
Sensor
sensors: 3100 *barometric transition rotation gps
Barometer: 0.777190 bar 2181.8 m
nav translation: 0.9574 m -8.2139 m 218.2309 m accuracies: 9.3936 m 9.3936 m 0.0000 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:45.15876 long:25.497299 satellites:7 height:2327.2 m hdop:1.3 vdoor: 1.9m hacc:3.8m vacc:5.3 flags:G3 's:smc:smc 3D solution'
north:5030218.143 m east:382421.272 m zone:35T
Initial pre position (3-coor):
0.7119 -0.695 0.000 -18.635
0.835 0.715 0.000 -0.980
0.000 0.000 1.000 6.048
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



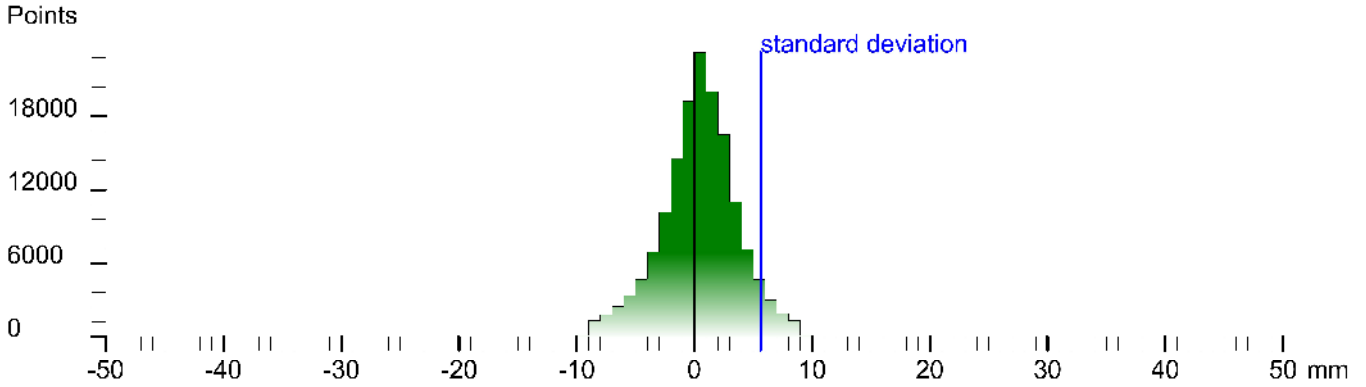
Scan position '67'

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

```
0.927084 -0.374857 -0.000302 -4.5778 m
0.374857 0.927083 0.000656 -18.5592 m
0.000034 -0.000721 1.000000 -4.4574 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:5.6 mm

Deviation histogram



Scan '67'

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: '67' - name: '67' - status: '102h' - registration: 'Cloud to Cloud' - status: 'Registered' - registration matrix: '0.927084 -0.374857 -0.000302 -4.5778 m
0.374857 0.927083 0.000656 -18.5592 m
0.000034 -0.000721 1.000000 -4.4574 m
0.000000 0.000000 0.000000 1.0000'
Sensor
sensors: 3100 * barometer transition rotation gps
Barometer: 0.777211 bar 218.59 m
nav translation: 7.6980 m 11.7847 m 2.813757 m accuracies: 2.1678 m 12.1678 m 0.0000 m
nav rotation: 0.0000 0.0000 516.7974 accuracies: 0.0000 0.0000 15.0000
upside-down: no
GPS lat:45.15848 long:25.497437 satellites:8 height:2325.8 m hdop:1.0 vdoor: 0.3 m hacc:4.0m vacc:4.2 flags:G3 's:sm:sm:sm 3D solution'
north:5030215.552 m east:382434.957 m zero:35T
Initial pre position (3-coor):
0.779 -0.685 0.000 -7.699
0.865 0.728 0.000 -4.504
0.000 0.000 1.000 6.222
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '68'

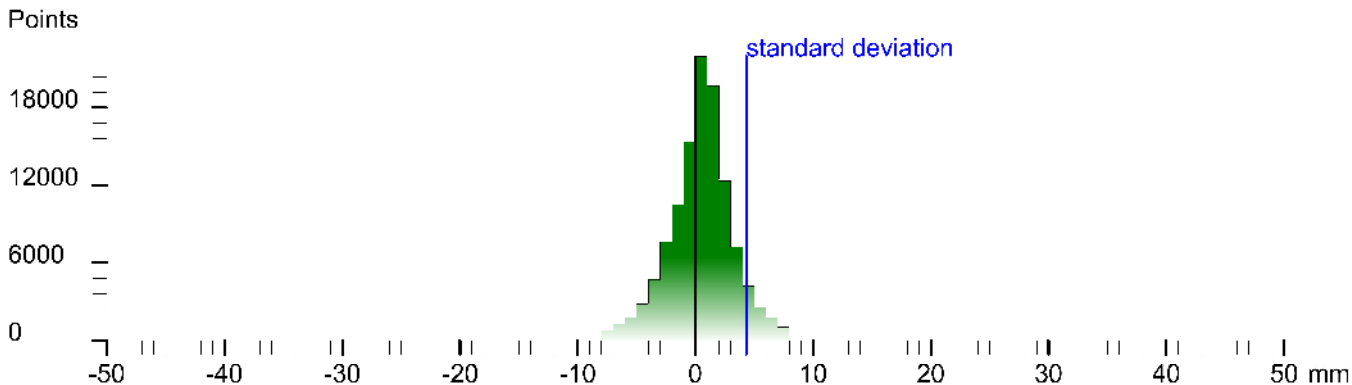
Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```

0.727834 -0.685754 -0.000258 13.0686 m
0.685754 0.727834 -0.000051 -25.1635 m
0.000223 -0.000140 1.000000 -1.8577 m
0.000000 0.000000 0.000000 1.0000
    
```

Result registration cloud to cloud standard deviation: 4.3 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 position: '68' - name: '68' - status: 'Registered with cloud to cloud' - registration matrix: '0.727834 -0.685754 -0.000258 13.0686 m; 0.685754 0.727834 -0.000051 -25.1635 m; 0.000223 -0.000140 1.000000 -1.8577 m; 0.000000 0.000000 0.000000 1.0000'
Sensor:
sensors: 3100 * barometer or transition rotation gps
Barometer: 0.776953 bar 2184.24 m
nav translation: 7.3118 m 27.1953 m 2184.1912 m accuracies: 19.4199 m * 9.4199 m 0.0000 m
nav rotation: 0.0000 0.0000 292.8886 accuracies: 0.0000 0.0000 15.0000
upside-down: no
GPS lat: 45.158+0 long: 25.497684 satellites: 8 height: 2326.6 m hdop: 1.0 vdoor: 1.4 m hacc: 3.0 m vacc: 3.6 flags: G3 's: a: a: no 3D solution'
north: 5030214.342 m east: 382451.338 m zone: 35T
Initial pre position (3-coo. tocoor):
0.389 -0.971 0.000 * 1.410
0.921 0.309 0.000 * -5.753
0.000 0.000 1.000 9.638
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'

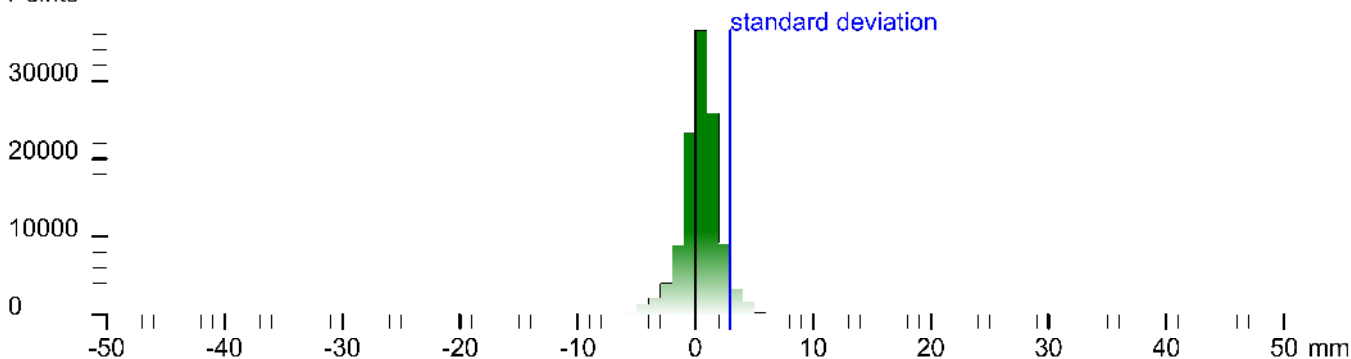
Registration matrix:

```
-0.931972 -0.362531 -0.000251 19.2390 m
0.362531 -0.931973 0.000053 -10.8064 m
-0.000253 -0.000042 1.000000 -0.5744 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:3.0 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

```
Scan position: '69' - name: '148:769' - status: '02' - type: 'Cloud to Cloud' - registration: 'Cloud to Cloud' - registration matrix: 'Cloud to Cloud' - registration standard deviation: '3.0' - status: 'Registered' - registration quality: 'High' - scan resolution: 'High' - scan quality: 'Normal'
Sensor
sensors: 3100 * barometric transition rotation gps
Barometer: 0.776912 bar 2184.67 m
nav translation: -5.9823 m 15.8896 m 2184.3884 m accuracies: 14.0567 m 14.0567 m 0.0000 m
nav rotation: 0.0000 0.0000 0.0000 * ba:9460 accuracies: 0.0000 0.0000 1s:0.0000
upside-down: no
GPS lat:45.15070 long:25.497667 satellites:7 height:2325.6 m hdop:1.4 vdoop:2.0 m hacc:4.5 m vacc:5.5 flags:G3 's:sm:sm:sm 3D solution'
north:5030282.776 m east:382453.267 m zcra:35T
Initial pre position (3-coor):
-0.913 0.408 0.000 0.350
-0.408 -0.913 0.000 -1.208
0.000 0.000 1.000 9.185
0.000 0.000 0.000 1.000
```

Level system info: dynamic compensator available.



Scan position '7'

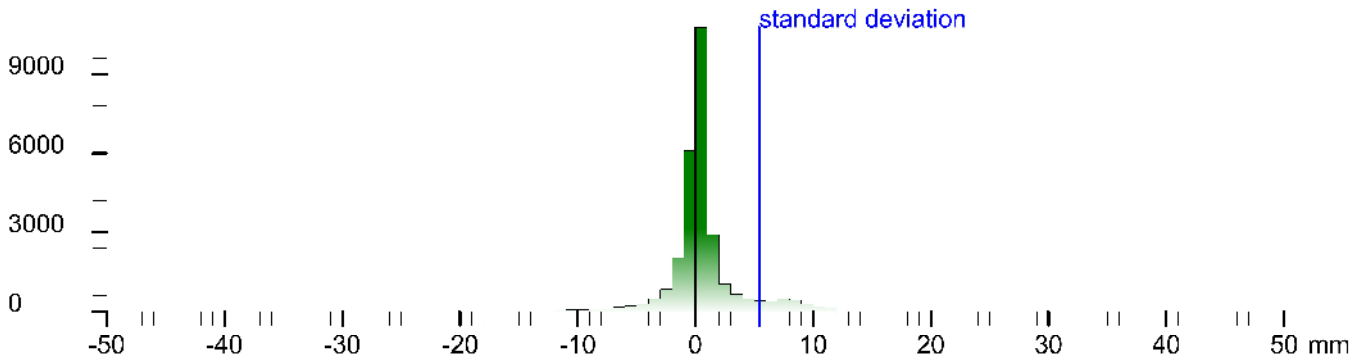
Scan position is member of group(s):
Status registration '[102h] registered with cloud to cloud'
Registration matrix:

```
0.979563 0.201136 -0.000411 8.1842 m  
-0.201136 0.979563 0.000705 -2.8612 m  
0.000545 -0.000608 1.000000 8.3379 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 5.4 mm

Deviation histogram

Points



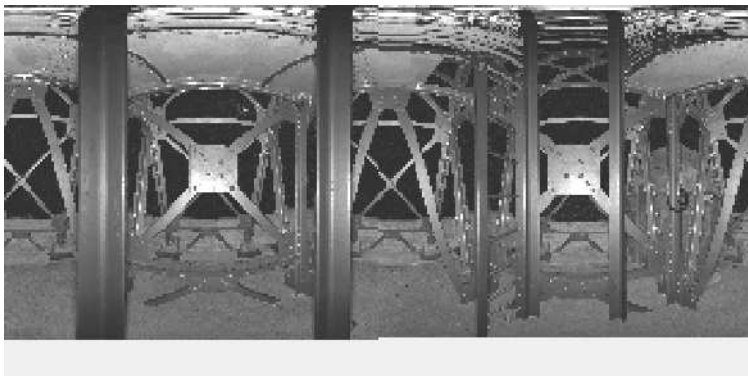
Scan '7'

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

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

```
comment  
operator  
Sensor  
sensors: 3100 *barome or transition rotation gps  
Barometer: 0.777864 bar 2174.85 m  
nav translation: 1.5627 m -1.1750 m 2174.4311 m accuracies: 0.0990 m 0.0690 m 0.0000 m  
nav rotation: 0.0000 0.0000 274.3478 accuracies: 0.0000 0.0000 15.0000  
upside-down: no  
GPS lat: 45.416006 long: 25.497530 satellites: 4 height: 2336.3 m hdop: 2.3 vdoop: 4.7 m hacc: 6.6m vacc: 13.0 tags: G3 'stand alone 3D solution'  
north: 5030263.214 m east: 382742.599 m zone: 35T  
Initial pre position (3.o.tccor):  
0.076 -0.997 0.000 -1.240  
0.997 0.076 0.000 1.563  
0.000 0.000 1.000 -0.749  
0.000 0.000 0.000 1.000
```

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



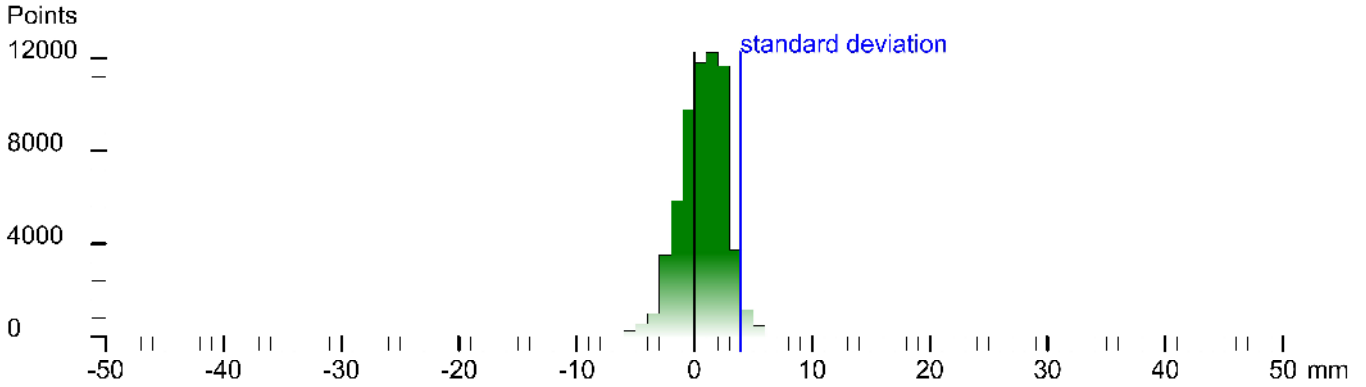
Scan position '70'

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

```
-0.164890 -0.986312 -0.000437 20.9795 m
0.986312 -0.164890 0.000557 5.9558 m
-0.000621 -0.000339 1.000000 -0.4676 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:3.9 mm

Deviation histogram



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 position: '70' name: '148:70' status: '70' type: 'Cloud Edge' data: '102h' registration: '102h' status: '102h' standard deviation: '3.9' scanner: 'Z+F IMAGER 5016' serial number: '5016-0100' firmware: '9.0.3.6562-0'
Sensor
sensors: 3100 *barome or transition rotation gps
Barometer: 0.776944 bar 2184.34 m
nav translation: -23.4200 m 9.8073 m 2183.973 m accuracies: 17.7696 m 17.7696 m 0.0000 m
nav rotation: 0.0000 0.0000 224.9936 accuracies: 0.0000 0.0000 1s.0000
upside-down: no
GPS lat:45.16122 long:25.497637 satellites:8 height:2327.6 m hdop:0.9 vdoor: 1.4 m hacc:3.0m vacc:4.0 flags:G3 's:sm:sm:sm 3D solution'
north:5030275.772 m east:382451.193 m zone:35T
Initial pre position (3-coor):
-0.707 -0.707 0.000 8.318
0.707 -0.707 0.000 -5.844
0.000 0.000 1.000 8.823
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'

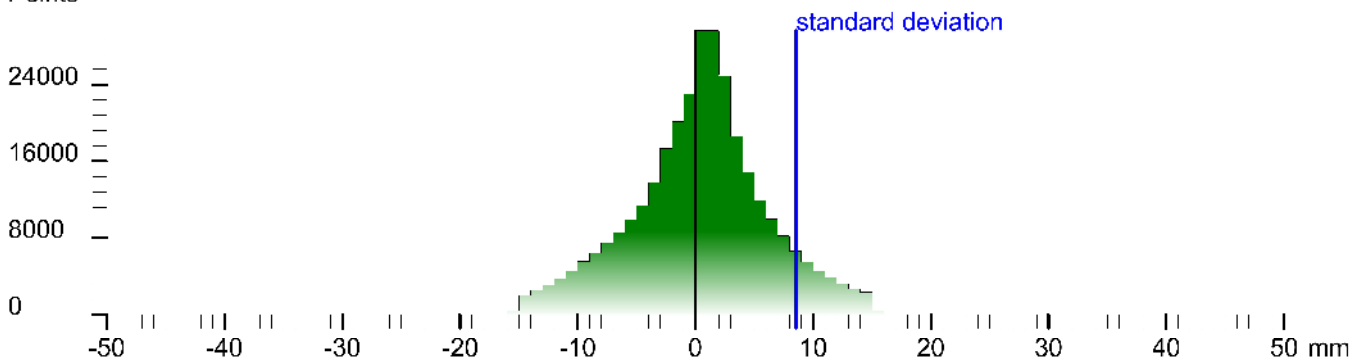
Registration matrix:

```
0.999159  0.040656  0.005427 -0.1917 m
-0.040678 0.999164  0.004089 -0.3296 m
-0.005256 -0.004306 0.999977  2.6036 m
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation:8.6 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 *barometer/transition rotation gps
Barometer: 0.776623 bar 2187.65 m
nav translation: 3.209 m -0.9167 m 2185.2607 m accuracies: 8.9330 m 8.9330 m 0.0007 m
nav rotation: 0.0000 0.0000 344.4400 accuracies: 0.0000 0.0000 15.0000
upside-down: no
GPS lat:45.16005 long:25.497408 satellites:7 height:2330.8 m hdop:1.1 vdoor:1.5 m hacc:3.3m vacc:5.5 flags:G3 's are above 3D solution'
north:5030263.383 m east:382433.048 m zcra:35T
Initial pre position (3-coor):
0.993 -0.268 0.000 -9.636
0.280 0.983 0.000 3.314
0.000 0.000 1.000 10.137
0.000 0.000 0.000 1.000
```

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



Scan position '72'

Scan position is member of group(s):

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

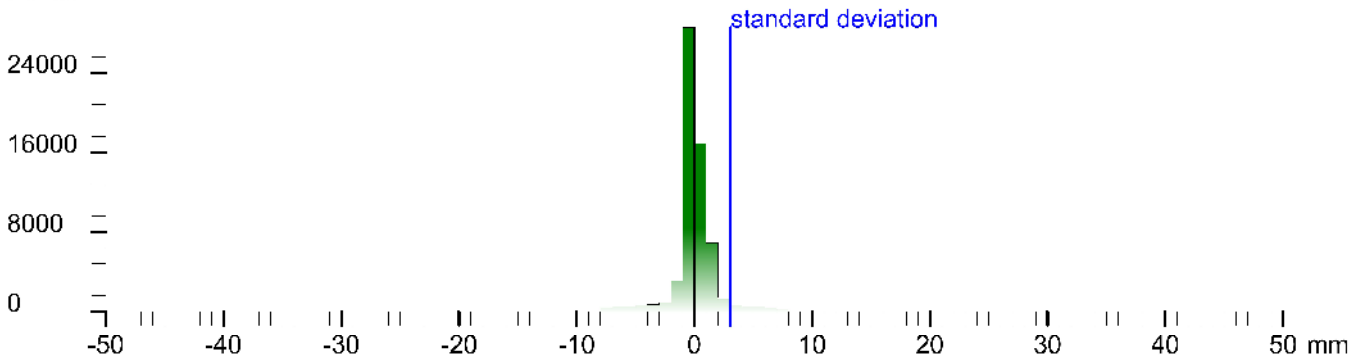
Registration matrix:

```
-0.421866  0.906659 -0.000271  6.4172 m  
-0.906659 -0.421866 -0.000158 -0.0667 m  
-0.000258  0.000179  1.000000  1.6127 m  
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation:3.1 mm

Deviation histogram

Points



Scan '72'

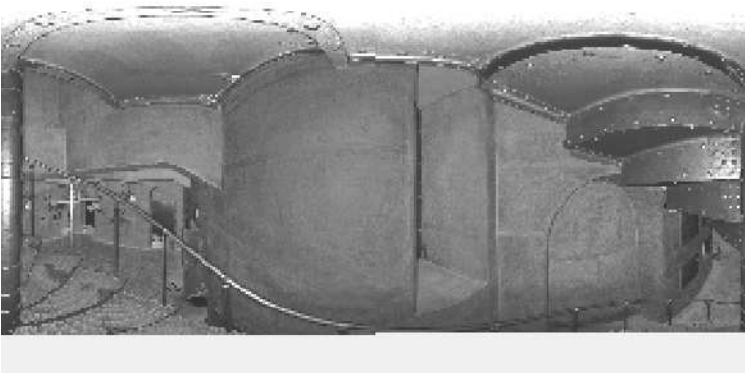
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

Sensor: 3096 *barometric transition rotation*
Barometer: 0.776777 bar 2186.06 m
nav translation: 0.0000 0.0000 0.21858479 m accuracies: 8.4344 m 8.4344 m 0.0000 m
nav rotation: 0.0000 0.0000 221.9e94 accuracies: 0.0000 0.0000 1s.0000
upside-down: no
Initial pos position (0 indoor)
-3.74 / -0.669 0.000 -8.836
0.659 -0 / 44 0.000 3.314
0.000 0.000 1.000 10.695
0.000 0.000 0.000 1.000

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



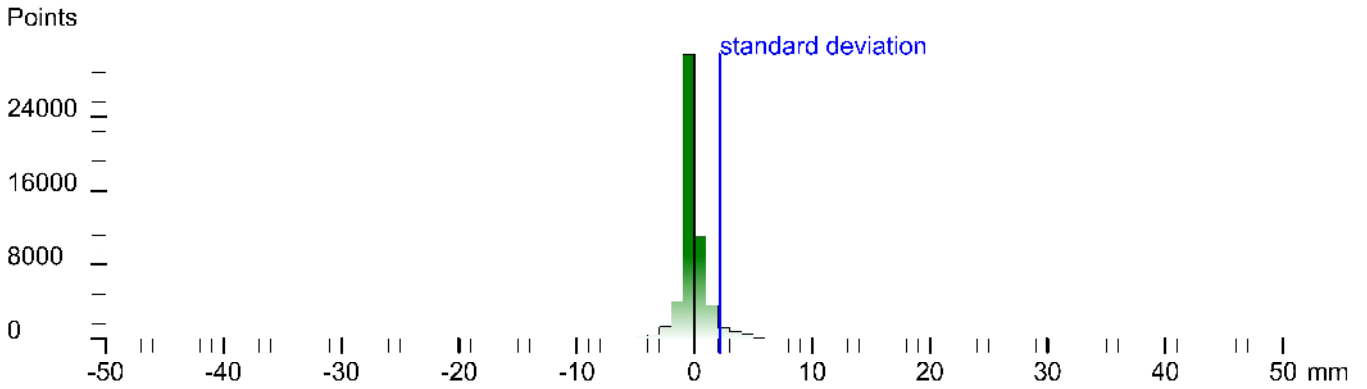
Scan position '73'

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

```
0.866819 -0.498624 -0.000024 10.8427 m
0.498624 0.866819 0.000262 -1.6020 m
-0.000110 -0.000239 1.000000 0.2407 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 2.2 mm

Deviation histogram



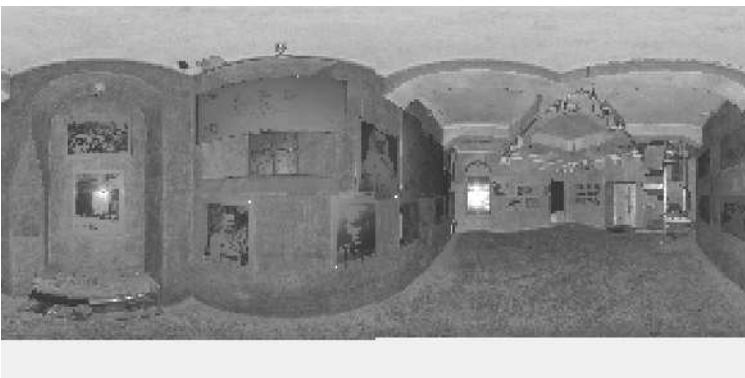
Scan '73'

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

Metadata	Value
comment	
operator	

Scan comment: null
 Sensors: 3096 *barome or transition rotation*
 Barometer: 0.776882 bar 2184.07 m
 nav translation: -3.8874 m -3.0233 m 2184.7527 m accuracies: 0.9853 m 0.9853 m 0.0000 m
 nav rotation: 0.0000 0.0000 242.7338 accuracies: 0.0000 0.0000 1s.0000
 up/down: no
 Initial pos position (0 indoor)
 -3.458 -0.889 0.000 -10.721
 0.889 -0.458 0.000 -0.309
 0.000 0.000 1.000 9.589
 0.000 0.000 0.000 1.000

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



Scan position '74'

Scan position is member of group(s):

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

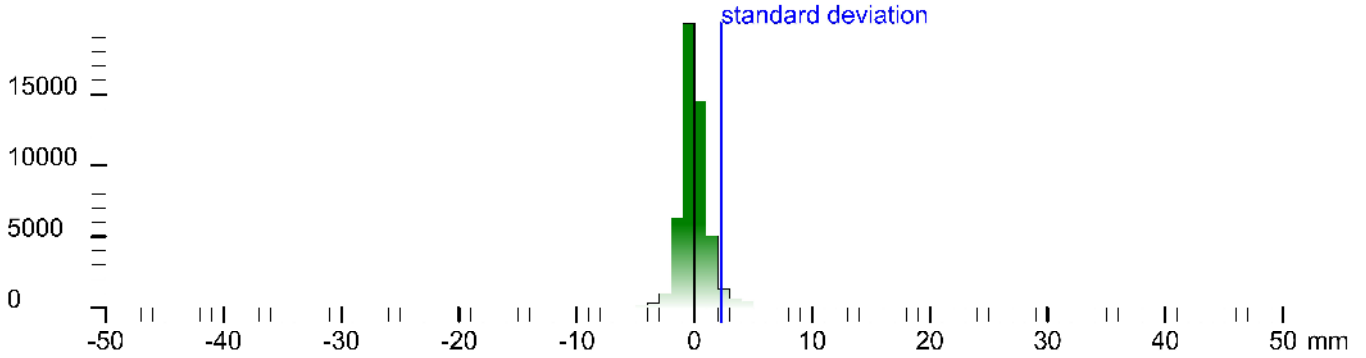
Registration matrix:

```
-0.849084 0.528259 -0.000129 9.3151 m  
-0.528259 -0.849084 -0.000344 -5.8661 m  
-0.000291 -0.000224 1.000000 0.2306 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:2.3 mm

Deviation histogram

Points



Scan '74'

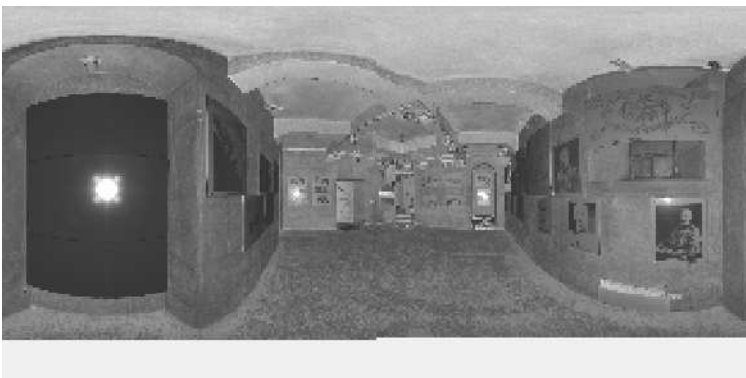
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Sensor: 3096 *barometer transition rotation*  
Barometer: 0.776903 bar 2184.76 m  
nav translation: 2.7192 m -1.0083 m 2184.5613 m accuracies: 0.58° S 0.58° S 0.0006 m  
nav rotation: 0.0000 0.0000 0.0000 0.0000 0.0000 0.0000 15.0000  
upside-down: no  
Initial pre position: (0/door)  
0.845 -0.326 0.000 -8.001  
0.326 0.845 0.000 -7.318  
0.000 0.000 1.000 9.408  
0.000 0.000 0.000 1.000
```

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



Scan position '75'

Scan position is member of group(s):

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

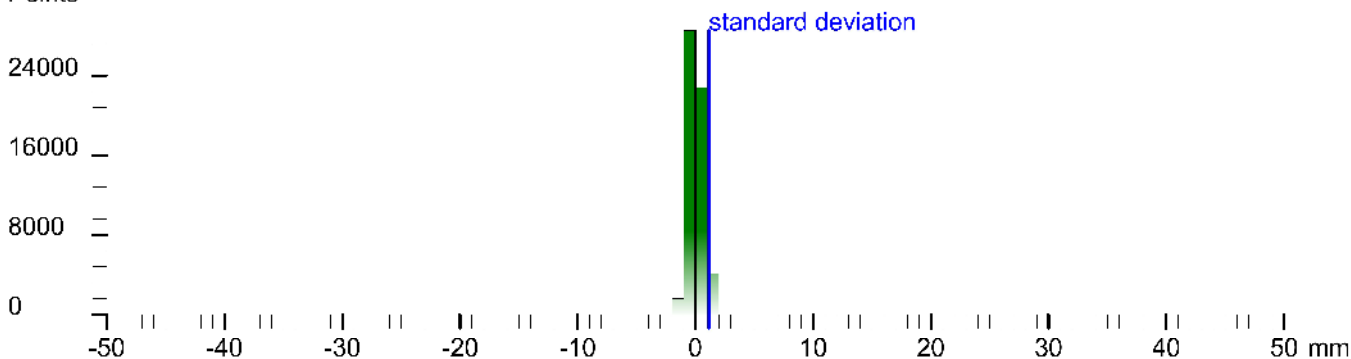
Registration matrix:

```
-0.307446 -0.951566 -0.000201 5.5755 m  
0.951566 -0.307446 0.000142 -4.0310 m  
-0.000197 -0.000148 1.000000 0.2308 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 1.1 mm

Deviation histogram

Points



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 comment: full_LPS_Builer_2013 - filename: 148-75 - number: 75 - path: C:\Users\Boris_Gardner\Desktop\Clouds\Boris_Gardner\Boris_Gardner\Boris_Gardner\75 - registration type: cloud to cloud - registration quality: cloud to cloud - scan resolution: High - scan quality: Normal  
Sensor  
sensors: 3096 *barometric transition rotation*  
Barometer: 0.776913 bar 2184.65 m  
nav translation: 0.5014 m -3.7810 m 2184.117 m accuracies: 5.5711 m 5.5711 m 0.0000 m  
nav rotation: 0.0000 0.0000 269.0144 accuracies: 0.0000 0.0000 15.0000  
upside-down: no  
Initial pre position (Girdoor)  
-3.017 -1.000 0.000 -7.500  
1.000 -0.017 0.000 -2.099  
0.000 0.000 1.000 8.961  
0.000 0.000 0.000 1.000
```

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



Scan position '76'

Scan position is member of group(s):

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

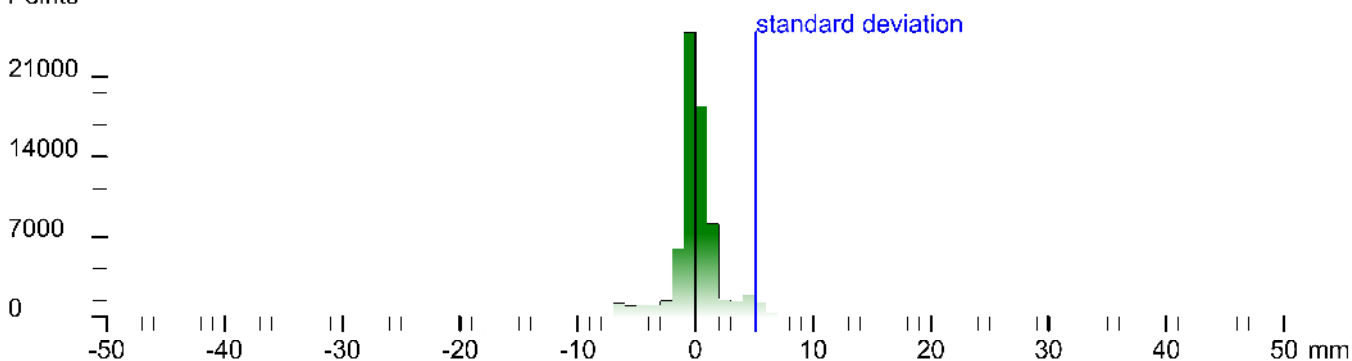
Registration matrix:

```
0.586152 0.810201 -0.000224 4.0052 m
-0.810201 0.586152 0.000130 -1.5221 m
0.000236 0.000105 1.000000 0.1957 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:5.1 mm

Deviation histogram

Points



Scan '76'

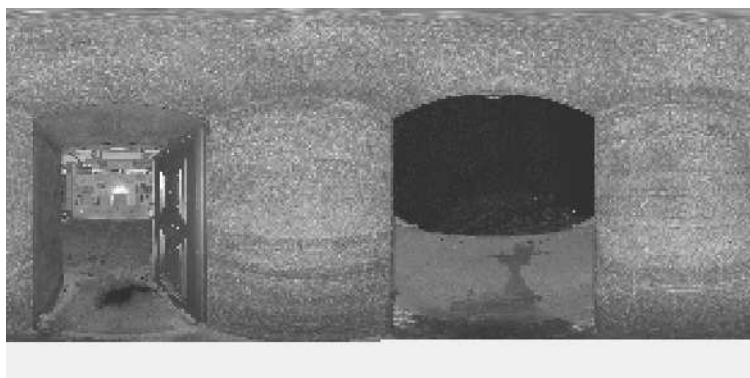
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan comment: full LPS (blue 303) + middle 148; 76' position '76' type 'Circular Edge Circular Edge Circular Edge' 'New registration' '0' scan 'New' 'position' 'new' 'date' '2016-11-14 12:00:00' '1847'
Sensor
sensors: 3096 'barome or transition rotation'
Barometer: 0.776888 bar 2184.8' m
nav translation: -1.2390 m 2.0604 m 2184.5276 m accuracies: 0.3053 m 0.3053 m 0.0000 m
nav rotation: 0.0000 0.0000 224.8:48 accuracies: 0.0000 0.0000 15.0000
upside-down: no
Initial pos position: (0 indoor)
-3.708 -0.705 0.000 -8.733
0.700 -0.709 0.000 -0.038
0.000 0.000 1.000 9.374
0.000 0.000 0.000 1.000
```

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



Scan position '77'

Scan position is member of group(s):

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

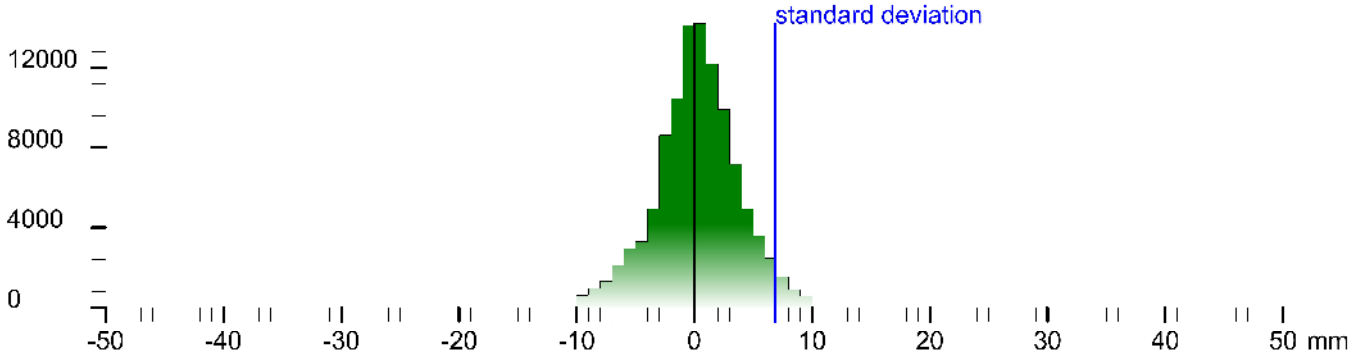
Registration matrix:

-0.704113	-0.710082	-0.003008	5.8906 m
0.710082	-0.704118	0.001320	-2.2209 m
-0.003055	-0.001206	0.999995	10.0231 m
0.000000	0.000000	0.000000	1.0000

Result registration cloud to cloud standard deviation:6.9 mm

Deviation histogram

Points



Scan '77'

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

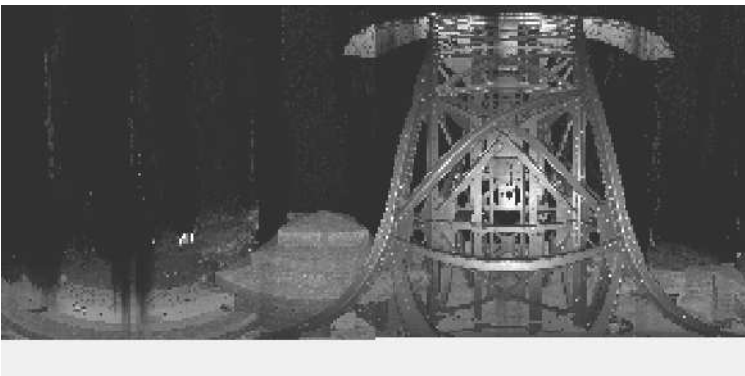
Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```

Sensor
sensors: 3100 *barome or transtion rotation gps
Barometer: 0.775965 bar 2194.45 m
nav translation: -2.7785 m 8.3913 m 2192.5190 m accuracies: 10.2812 m 10.2812 m 0.0007 m
nav rotation: 0.0000 0.0000 -03.176/ accuracies: 0.0000 0.0000 1s.0000
upside-down: no
GPS lat:45.15095 long:25.497480 satellites:5 height:234.15 m hdop:3.4 vdoop:2.8 m hacc:9.7m vacc:15.0 tags:G3 *stand alone 3D solution
Initial pre position (3co. tocor):
-0.228 0.974 0.000 -11.513
-0.974 -0.228 0.000 9.353
0.000 0.000 1.000 17.366
0.000 0.000 0.000 1.000
  
```

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



Scan position '78'

Scan position is member of group(s):

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

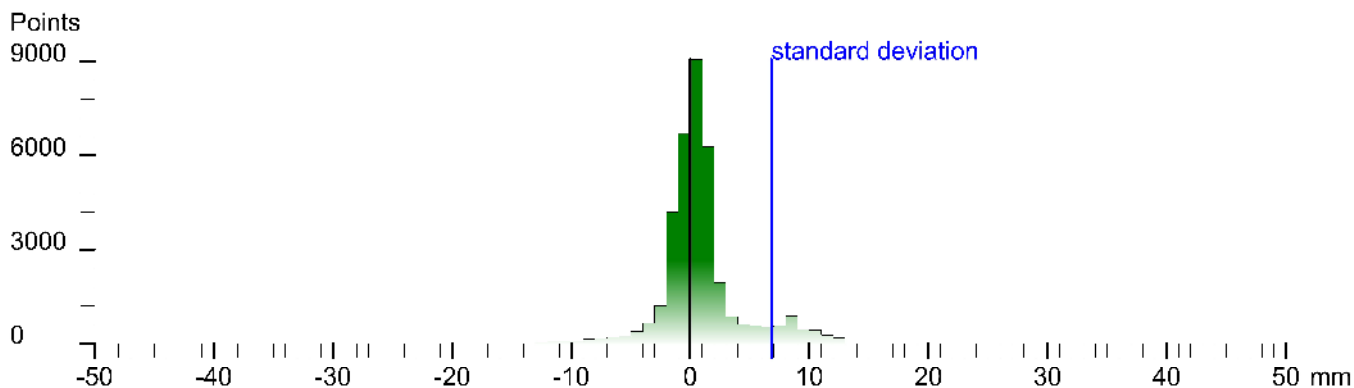
Registration matrix:

```

0.740649 -0.671775 0.012578 9.4777 m
0.671768 0.740742 0.005356 -0.9859 m
-0.012915 0.004482 0.999907 10.0911 m
0.000000 0.000000 0.000000 1.0000
  
```

Result registration cloud to cloud standard deviation: 6.8 mm

Deviation histogram



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 position: local file: Full Scan Name: 0140781016-12-14134046-78-Cloud to Cloud Error Count: 0 Error: 0 Status: 100% Success: 100% Scan Name: 0140781016-12-14134046-78-Cloud to Cloud Error Count: 0 Error: 0 Status: 100% Success: 100%
Sensor
sensors: 3100 *barometric transition rotation gps
Barometer: 0.775945 bar 2194.66 m
nav translation: 0.5519 m 0.5928 m 2192.6775 m accuracies: 8.4375 m 8.4375 m 0.0000 m
nav rotation: 0.0000 0.0000 0.0000 308.6622 accuracies: 0.0000 0.0000 15.0000
upside-down: no
GPS lat: 45.16023 long: 25.497543 satellites: 7 height: 2339.4 m hdop: 1.2 vdoor: .5 m hacc: 3.4 m vacc: 5.5 flags: G3 's' are able 3D solution'
north: 5030264.890 m east: 382413.675 m zone: 35T
Initial pre position (3-coo, tocoor):
0.675 -0.781 0.000 0.758
0.761 0.825 0.000 4.763
0.000 0.000 1.000 17.621
0.000 0.000 0.000 1.000
  
```

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



Scan position '79'

Scan position is member of group(s):

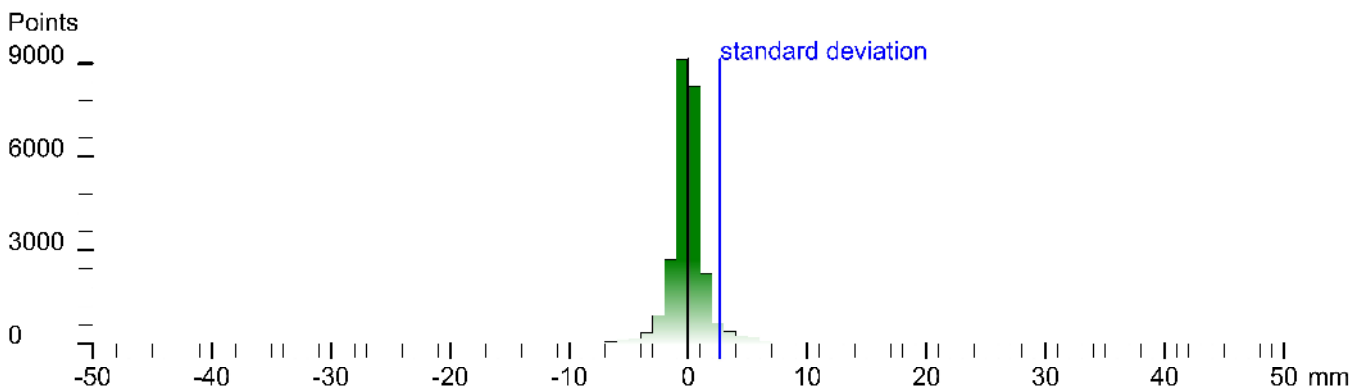
Status registration '[102h] registered with cloud to cloud'

Registration matrix:

```
-0.267161 -0.963653 -0.000274 6.7074 m  
0.963652 -0.267161 0.000622 -1.0862 m  
-0.000673 -0.000097 1.000000 8.2021 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:2.7 mm

Deviation histogram



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: null  
Sensor  
sensors: 3096 *barometric transition rotation*  
Barometer: 0.776008 bar 2193.07 m  
nav translation: -7.8826 m -2.1949 m 2192.2000 m accuracies: 0.2516 m 0.2516 m 0.0000 m  
nav rotation: 0.0000 0.0000 532.4490 accuracies: 0.0000 0.0000 15.0000  
upside-down: no  
Initial pre position: (Girdoor)  
0.537 -0.874 0.000 -7.725  
0.544 0.537 0.000 2.268  
0.000 0.000 1.000 17.707  
0.000 0.000 0.000 1.000
```

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



Scan position '8'

Scan position is member of group(s):

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

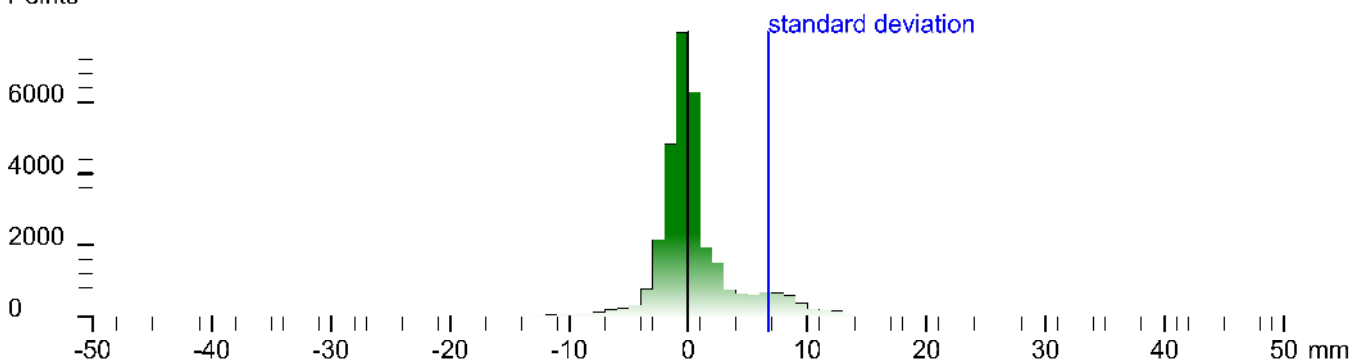
Registration matrix:

```
-0.847711 0.530458 0.000102 8.8681 m  
-0.530458 -0.847711 0.000387 -1.4257 m  
0.000292 0.000274 1.000000 8.2981 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:6.7 mm

Deviation histogram

Points



Scan '8'

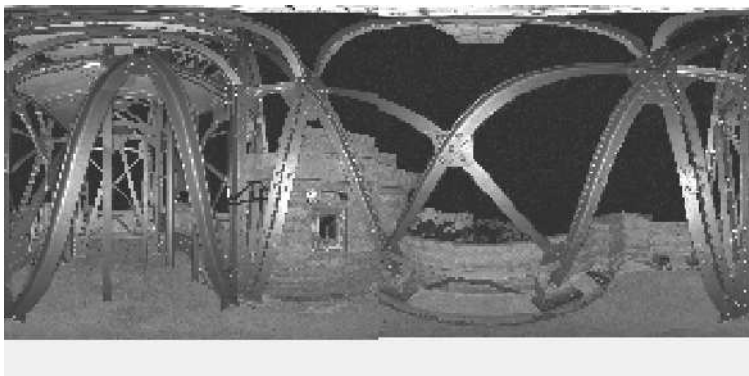
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata **Value**
comment
operator

```
Scan position: '8' [102h] registered with cloud to cloud  
Sensor  
sensors: 3100 *barometric transition rotation gps  
Barometer: 0.777945 bar 2174.02 m  
nav translation: -3.3920 m 1.7754 m 2174.0227 m accuracies: 0.0657 m 0.0657 m 0.0000 m  
nav rotation: 0.0000 0.0000 -18.8699 accuracies: 0.0000 0.0000 16.0000  
upside-down: no  
GPS lat:45.16016 lon:25.497494 satellites:4 height:2336.7 m hdop:2.3 vdoor: 1.0 m hacc:10.0 m vacc:20.0 m flags:G2 *stand alone 2D solution  
north:5030264.115 m east:382439.778 m zone:35T  
Initial pre position (3-coor):  
-0.483 0.876 0.000 -1.632  
-0.876 -0.483 0.000 3.338  
0.000 0.000 1.000 -1.131  
0.000 0.000 0.000 1.000
```

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



Scan position '80'

Scan position is member of group(s):

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

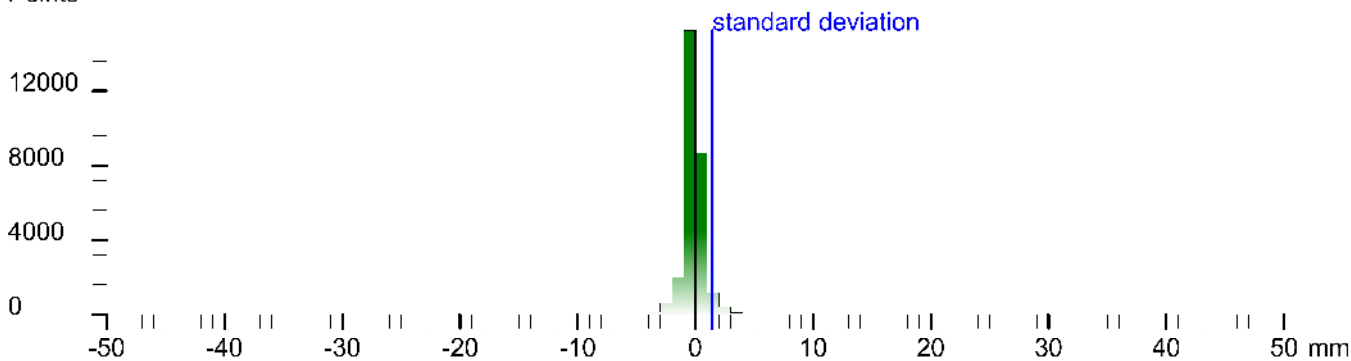
Registration matrix:

0.016533	0.999864	0.000413	6.9192 m
-0.999864	0.016532	0.000214	-0.6618 m
0.000208	-0.000416	1.000000	6.9547 m
0.000000	0.000000	0.000000	1.0000

Result registration cloud to cloud standard deviation: 1.5 mm

Deviation histogram

Points



Scan '80'

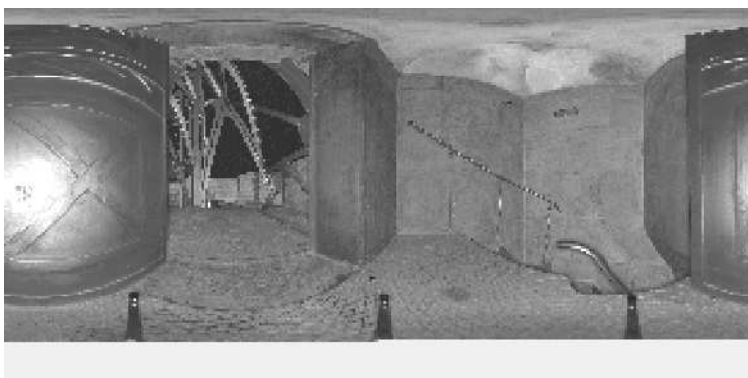
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

Sensor: 3096 *barometric transition rotation*
Barometer: 0.776168 bar 2192.35 m
nav translation: -1.6725 m 2.1025 m 219.3289 m accuracies: 0.18° 0 m 0.18° 0 m 0.00° 4 m
nav rotation: 0.0000 0.0000 49.4696 accuracies: 0.0000 0.0000 16.0000
upside-down: no
Initial pre position: (Girdoor)
-3.861 0.508 0.000 -8.798
-3.868 -0.867 0.000 4.451
0.000 0.000 1.000 16.676
0.000 0.000 0.000 1.000

Level system info: dynamic compensator available.



Scan position '81'

Scan position is member of group(s):

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

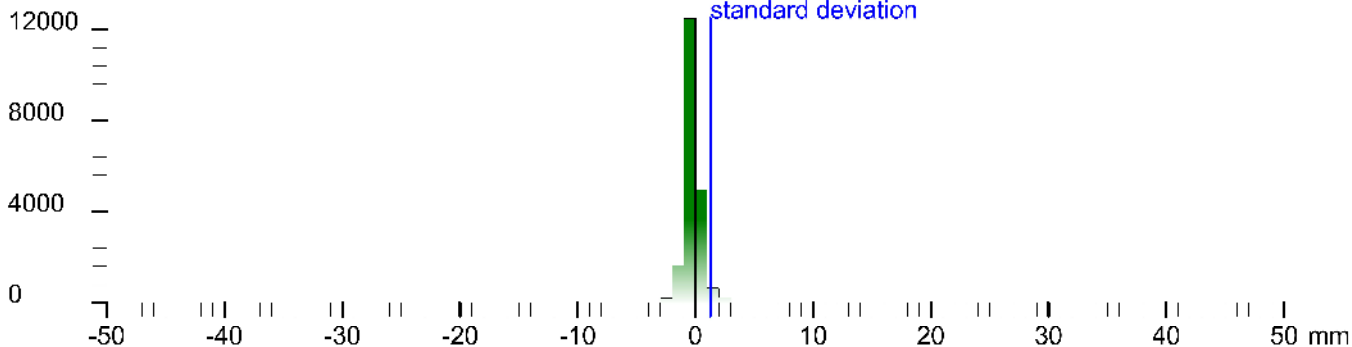
Registration matrix:

```
-0.639699 -0.768627 -0.000292 6.9463 m  
0.768627 -0.639699 0.000537 0.3852 m  
-0.000599 0.000118 1.000000 6.2309 m  
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 1.3 mm

Deviation histogram

Points



Scan '81'

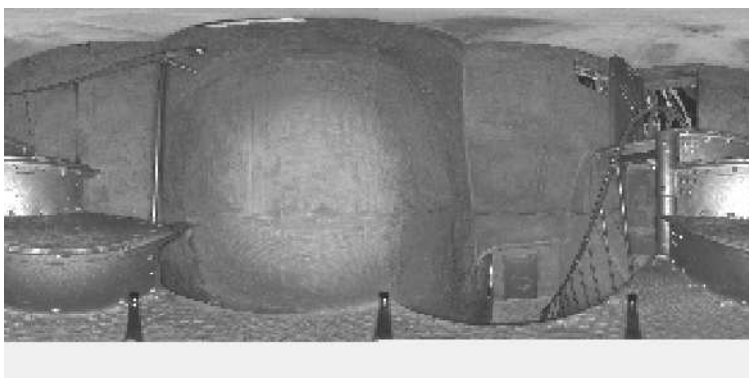
Scanner 'Z+F IMAGER 5016' serial number '5016-0100' Firmware 9.0.3.6562-0

Scan resolution 'High' quality 'Normal'

Metadata	Value
comment	
operator	

```
Scan position: '81' [102h] registered with cloud to cloud  
Sensor  
sensors: 3096 *barometric transition rotation*  
Barometer: 0.776173 bar 2192.3 m  
nav translation: -1.0635 m 3.3768 m 218° .5137 m accuracies: 5.6750 m 5.6750 m 0.0006 m  
nav rotation: 0.0000 0.0000 *12.1390 accuracies: 0.0000 0.0000 16.0000  
upside-down: no  
Initial pre position (Girdoor)  
-3.377 0.926 0.000 -9.601  
-3.926 -0.377 0.000 4.627  
0.000 0.000 1.000 16.360  
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'

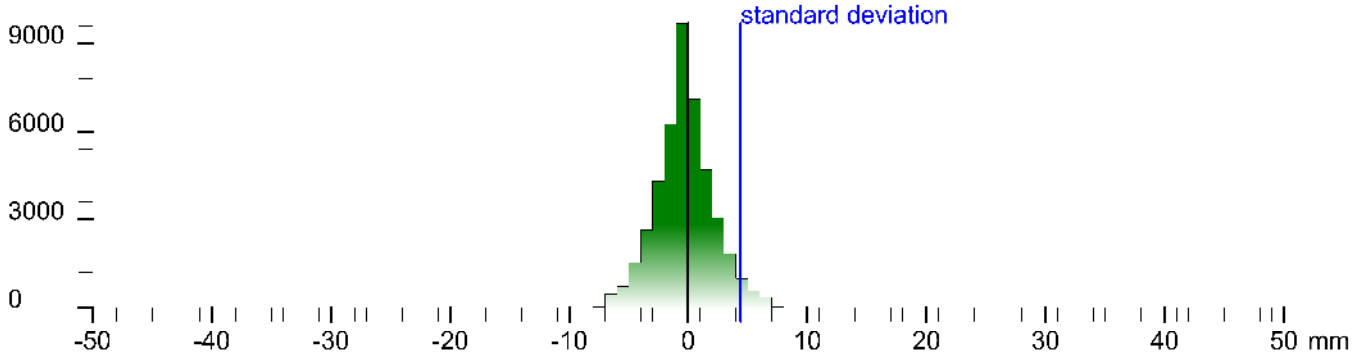
Registration matrix:

```
-0.803057  0.595904  -0.000474  -1.5130 m
-0.595904  -0.803057  0.000314  -10.0309 m
-0.000194  0.000535  1.000000  -3.1698 m
0.000000  0.000000  0.000000  1.0000
```

Result registration cloud to cloud standard deviation:4.4 mm

Deviation histogram

Points



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 position: '148' - name: '148' - scan: '82' - group: 'Cloud to Cloud' - status: 'Registered with cloud to cloud' - standard deviation: 4.4 mm - resolution: 'High' - quality: 'Normal'
Sensor
sensors: 3096 *barometric transition rotation*
Barometer: 0.776992 bar 2183.84 m
nav translation: 2.0076 m 7.2292 m 2183.6290 m accuracies: 8.1755 m 9.1755 m 0.0006 m
nav rotation: 0.0000 0.0000 *00.8961 accuracies: 0.0000 0.0000 16.0000
upside-down: no
Initial pre position: (Girdoor)
-3.180 0.984 0.000 -7.853
-0.984 -0.180 0.000 12.307
0.000 0.000 1.000 8.476
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 '[10123h]' preregistered with cloud to cloud, manually'

Registration matrix:

-0.914429	-0.404670	-0.007958	-2.5858 m
0.404736	-0.914377	-0.010274	-8.8131 m
-0.003119	-0.012616	0.999915	-3.2144 m
0.000000	0.000000	0.000000	1.0000

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 comment: null
Sensor

sensors: 3096 "barometric (translation: rotation)"

Barometer: 0.776992 bar 2163.84 m

nav translation: -3.8021 m -0.9362 m 2163.7917 m accuracies: 5.7453 m 5.7453 m 0.0000 m

nav rotation: 0.00000 0.00000 65.6769 accuracies: 0.0000 0.0000 15.0000

upside-down: no

Initial pre position (0/door)

0.412 0.917 0.000 -8.666

-0.911 0.412 0.000 11.118

0.000 0.000 1.000 5.036

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 '[10123h]' preregistered with cloud to cloud, manually'

Registration matrix:

0.728911	0.684606	0.002322	-0.1081 m
-0.684441	0.728802	-0.019789	-9.1350 m
-0.015240	0.012835	0.999801	-3.0414 m
0.000000	0.000000	0.000000	1.0000

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: 3096 "barometric (translation: rotation)"
Barometer: 0.776995 bar 2183.87 m
nav translation: 0.5039 m -3.6169 m 2183.3212 m accuracies: 5.5109 m 5.5109 m 0.0000 m
nav rotation: 0.0000 0.0000 2.222108 accuracies: 0.0000 0.0000 15.0000
upside-down: no
Initial pre position (0:indoor)
0.039 0.999 0.000 -8.751
0.999 0.039 0.000 10.501
0.000 0.000 1.000 5.171
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'

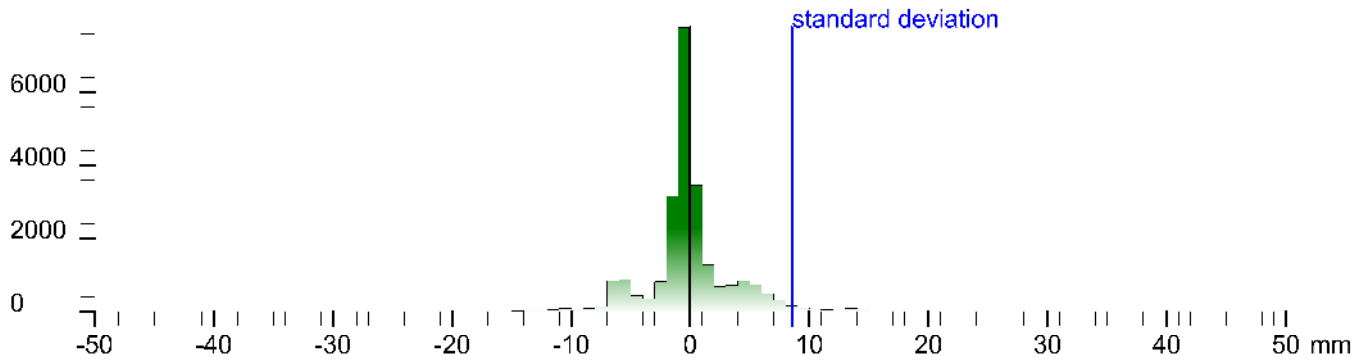
Registration matrix:

```
-0.860102 -0.510123 -0.000807 -0.4928 m
0.510123 -0.860103 0.000711 -6.3140 m
-0.001057 0.000200 0.999999 -3.2112 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation: 8.5 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	Sensor: 3096 *barome or transition rotation*
	Barometer: 0.776954 bar 2184.23 m
	nav translation: 0.2223 m -0.3633 m 2182.7476 m accuracies: 5.3125 m 5.3125 m 0.0000 m
	nav rotation: 0.0000 0.0000 0.0000 accuracies: 0.0000 0.0000 15.0000
	upside-down: no
	Initial pre position: (Girdoor)
	0.596 -0.893 0.000 -7.929
	0.603 0.096 0.000 10.748
	0.000 0.000 1.000 7.584
	0.000 0.000 0.000 1.000

Level system info: dynamic compensator available.



Scan position '86'

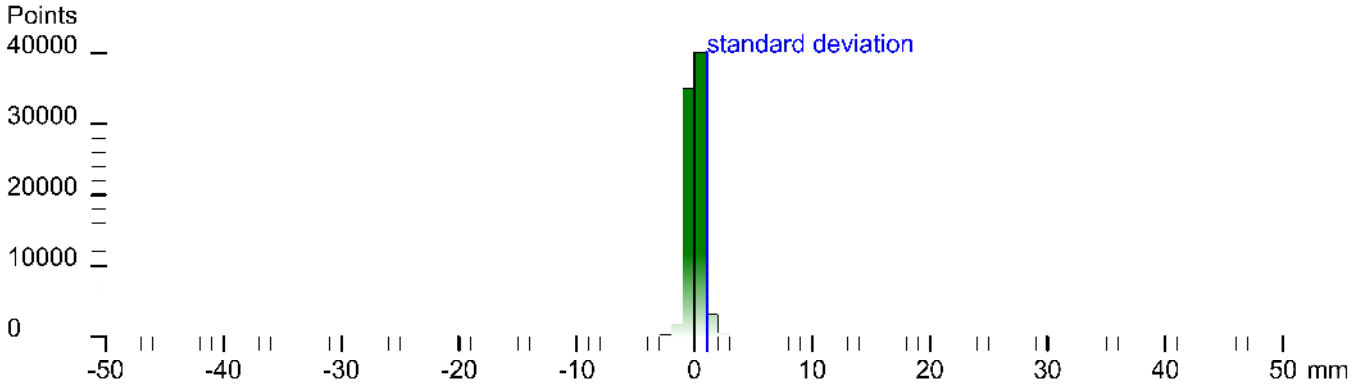
Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```

-0.954612 -0.297855 -0.000822 -0.0197 m
 0.297854 -0.954612  0.000725 -3.1556 m
-0.001000  0.000447  0.999999 -3.2065 m
 0.000000  0.000000  0.000000  1.0000
  
```

Result registration cloud to cloud standard deviation: 1.0 mm

Deviation histogram



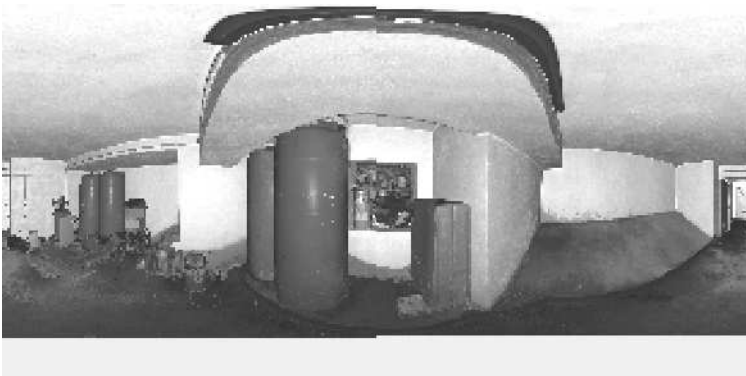
Scan '86'

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 position: '44' [102h] registered with cloud to cloud'
Sensor
 sensors: 3096 '*barometric transition rotation'
 Barometer: 0.776959 bar 2184.19 m
 nav translation: 0.94111 m 3.2307 m 2184.0022 m accuracies: 0.8124 m 0.8124 m 0.0007 m
 nav rotation: 0.0000 0.0000 0.0000 264.6036 accuracies: 0.0000 0.0000 1s.0000
 upside-down: no
 Initial position (0/door)
 -3.09 / -0.986 0.000 -6.985
 0.996 -0.094 0.000 3.378
 0.000 0.000 1.000 8.849
 0.000 0.000 0.000 1.000

Level system info: dynamic compensator available.



Scan position '87'

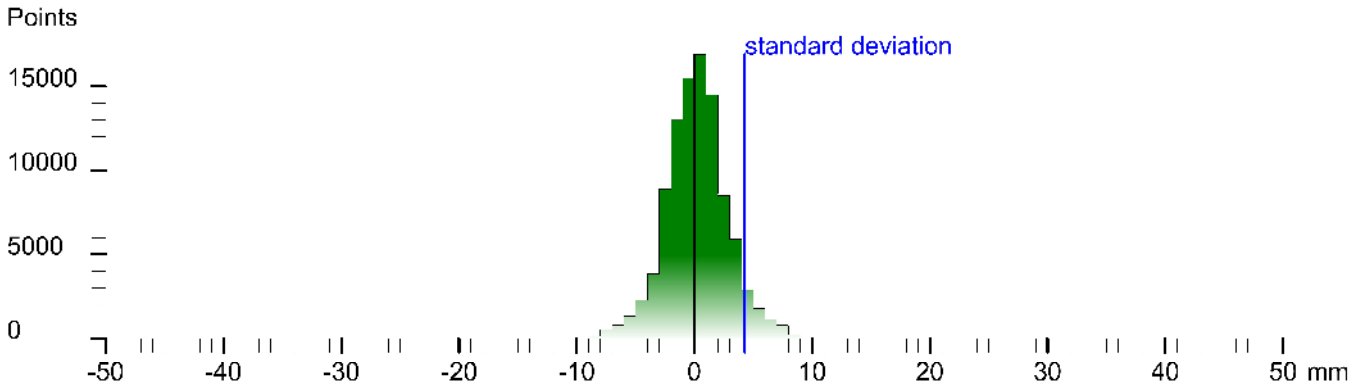
Scan position is member of group(s):
 Status registration '[102h] registered with cloud to cloud'
 Registration matrix:

```

0.999525  0.030844  -0.000116  -0.8329 m
-0.030844  0.999525  0.000678  10.4603 m
0.000137  -0.000675  1.000000  -2.0141 m
0.000000  0.000000  0.000000  1.0000
  
```

Result registration cloud to cloud standard deviation:4.3 mm

Deviation histogram



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 position: full 1.938m x 3.31m x 1.48m 87 points Cloud to Cloud registration matrix: 0.999525 0.030844 -0.000116 -0.8329 m
Sensor
sensors: 3100 *barometric transition rotation gps
Barometer: 0.776805 bar 2185.78 m
nav translation: 10.3670 m 17.1925 m 2 *81.9282 m accuracies: * 5.3810 m 15.3810 m 0.0000 m
nav rotation: 0.0000 0.0000 0.0000 0.0000 0.0000 0.0000 0.0000 0.0000 0.0000 0.0000
upside-down: no
GPS lat:45.16073 long:25.497386 satellites:6 height:2326.6m hdop:1.4 vdop:1.9m hacc:7.9m vacc:8.2 flags:G3 's:anc:slbrn 3D solution'
north:5030270.667 m east:382429.451 m zone:35T
Initial pre position (3-coo. tocoor)
0.994 -0.106 0.000 -13.457
0.106 0.994 0.000 10.605
0.000 0.000 1.000 9.775
0.000 0.000 0.000 1.000
  
```

Level system info: dynamic compensator available.



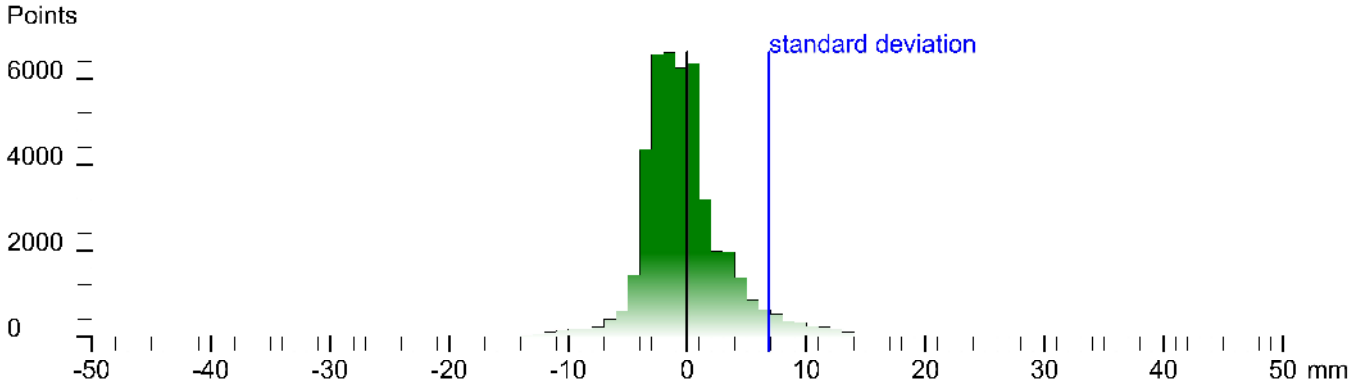
Scan position '9'

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

```
0.511306 0.859399 -0.000606 11.2751 m
-0.859397 0.511303 -0.002459 -1.4108 m
-0.001804 0.001778 0.999997 8.3220 m
0.000000 0.000000 0.000000 1.0000
```

Result registration cloud to cloud standard deviation:6.9 mm

Deviation histogram



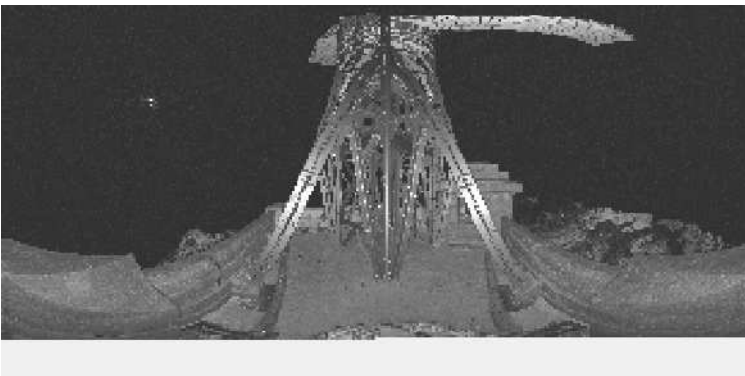
Scan '9'

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 position: '102h' registered with cloud to cloud
Sensor
sensors: 3100 *barometer/transition rotation/gps
Barometer: 0.777976 bar 2173.7 m
nav translation: 0.9274 m -1.1285 m 2173.0735 m accuracies: 5.83° 9 m 5.83° 9 m 0.0005 m
nav rotation: 0.0000 0.0000 0.2811 / accuracies: 0.0000 0.0000 0.0000
upside-down: no
GPS lat:45.16019 long:25.497532 satellites:7 height:2333.3 m hdop:1.0 vdoop: 1.8 m hacc:3.8m vacc:6.5 flags:G3 's are above 3D solution'
north:5030264.783 m east:382412.772 m zcra:35T
Initial pre position (3-coo. tooor):
0.950 0.314 0.000 -0.11°
-0.311 -0.950 0.000 4.355
0.000 0.000 1.000 -2.080
0.000 0.000 0.000 1.000
```

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



Labels

No labels stored in project

Links

No links stored in project

Summary

Number of scans: **87** used in **87** scan positions

Point clouds: **0**

Scans with color: **0** mapped **0**

Scans with thermal data: **0** mapped **0**

Scans with errors:**0** warnings:**1** 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 **87** scan positions

First scan taken at: **29.7.2021 08:47:26** last scan at: **30.7.2021 13:32:23**

Duration: **1d 4h 44min 57sec**