



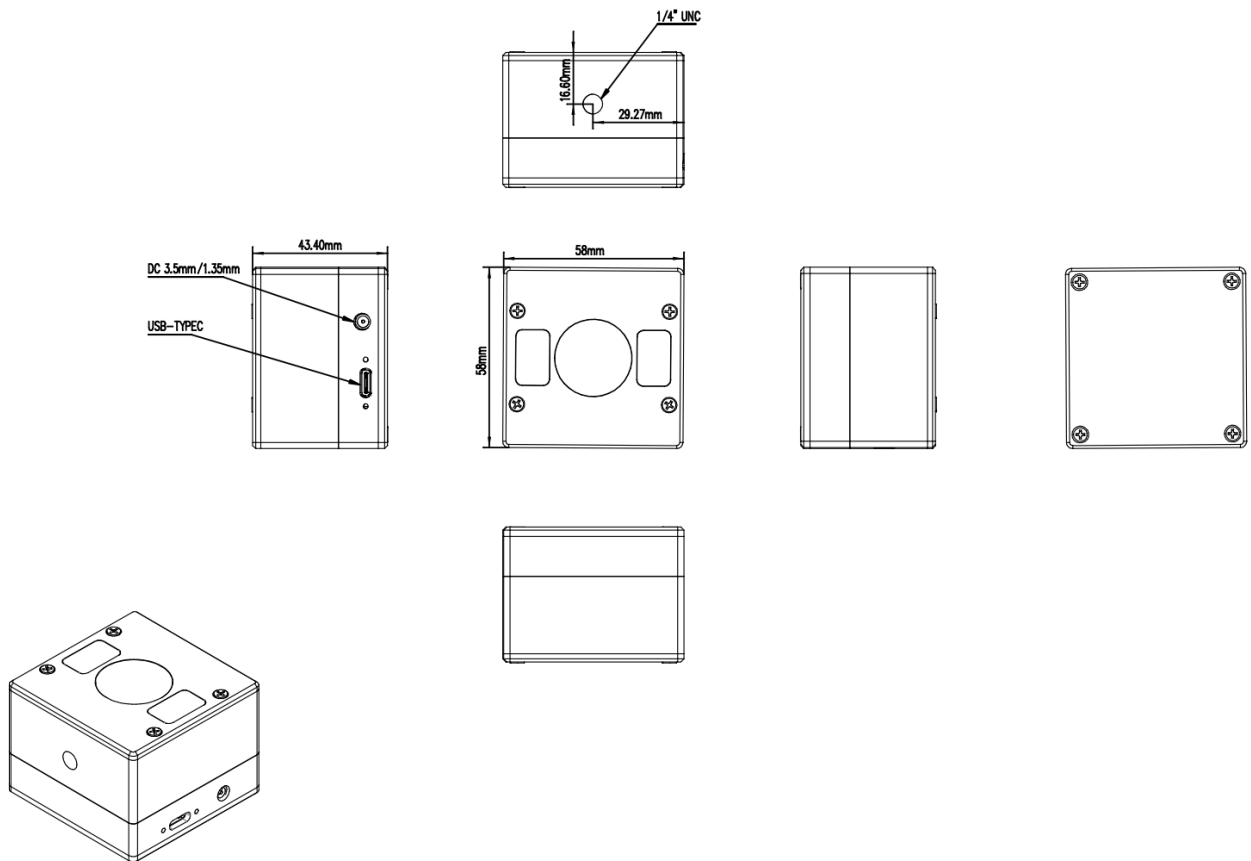
DepthEye S2

VGA resolution TOF camera

Robot obstacle avoidance, volume measurement, object recognition, etc

Model	DepthEye S2 H67V
Pixel Size	10.0 μm (H) \times 10.0 μm (V)
Resolution/FPS	0.3MP 640 x 480 px/ Max 30 FPS
Dimension & Weight	L:58 x W:58 x H:44 mm / 295 g
Accuracy	$\pm 10\text{mm}$ < 1.0 meter $\pm 5\text{mm} + 0.5\%$ of depth when ≥ 1.0 meter
Temporal Noise	Standard deviation less than 2mm at 1m Standard deviation less than 4mm at 2m Standard deviation less than 10.5mm at 4m (See Appendix for detailed data)
Measured Range	0.5m up to 4.0m
FOV	H67° x V51°
Data interface	USB 3.1 Gen1 /Type C
Power Consumption	12V/ 1A (Peak) /0.5A(Average)
Illumination	4 x VCSEL @ 850nm
Operating Temperature	-10°C – 60°C
Platform Support	Windows/Linux/Mac
CPU	SSC9381G (With 1Tops computing power)
SDK Language Support	C++/Python

Three views



Technical Support

SDK & Documents

<https://github.com/pointcloudAI/libDepthEye>

Support email

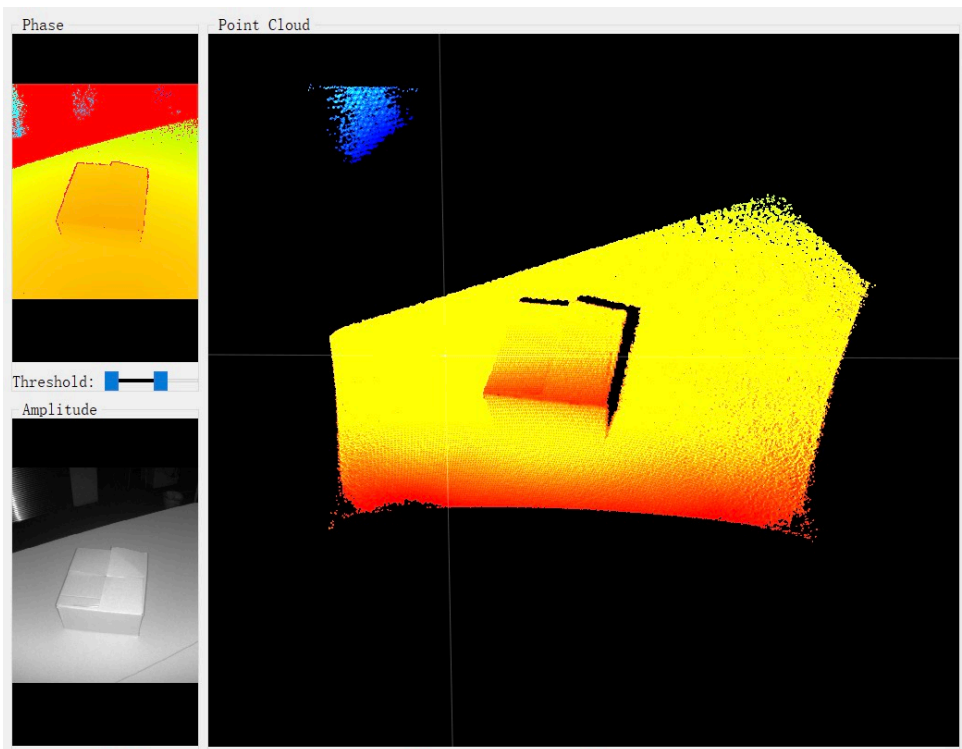
sdk@pointcloud.ai

For SSC9381G

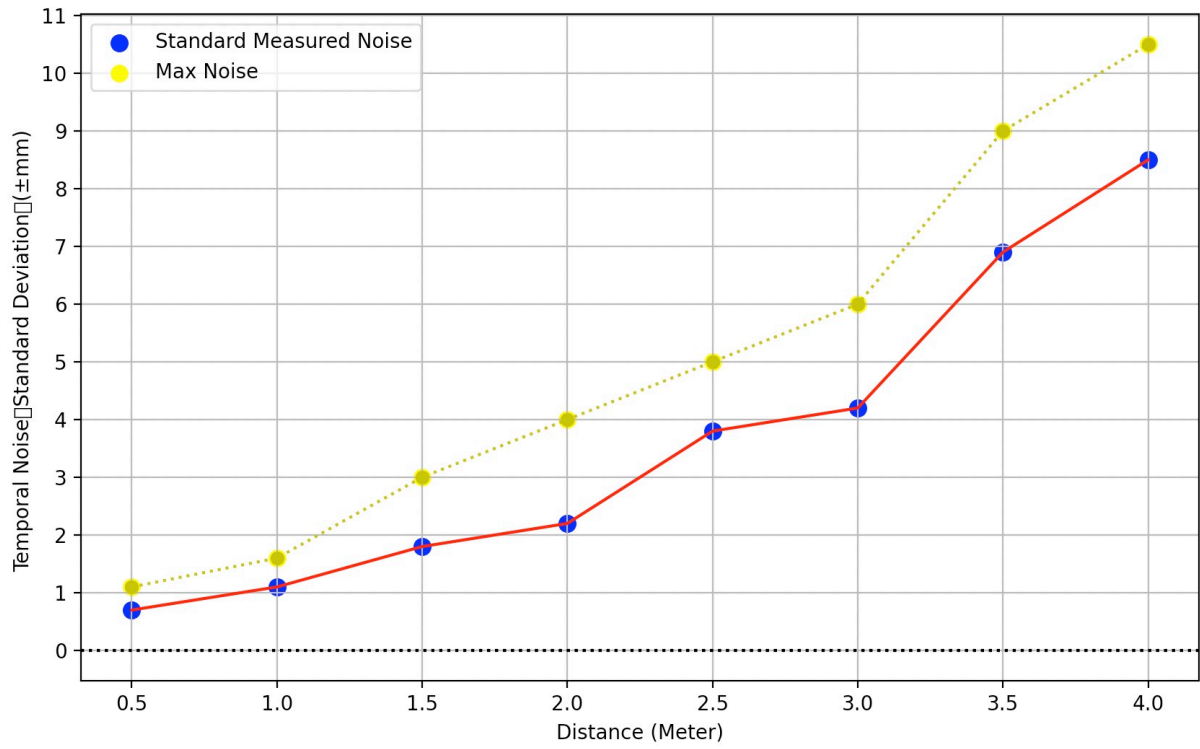
There are plans to open the SDK on AI in the future. The exact time has not been confirmed

Appendix:

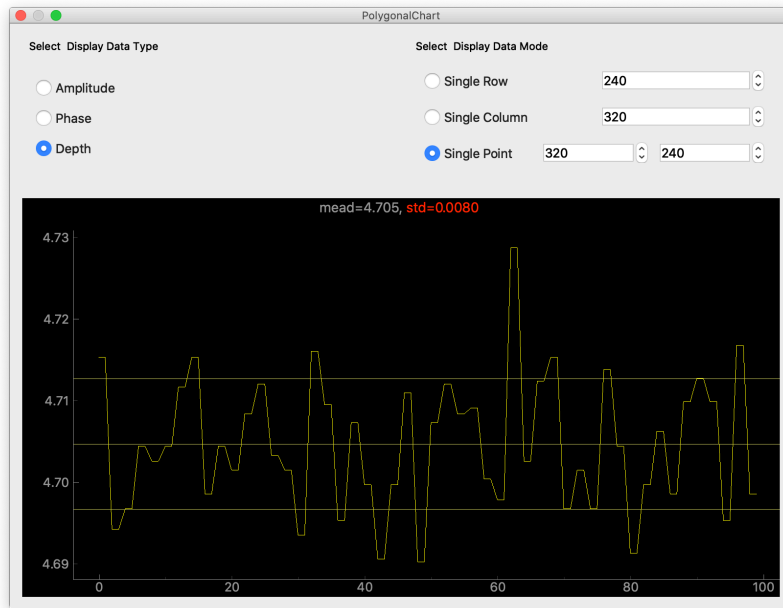
Depth Image / IR Image / PointCloud View



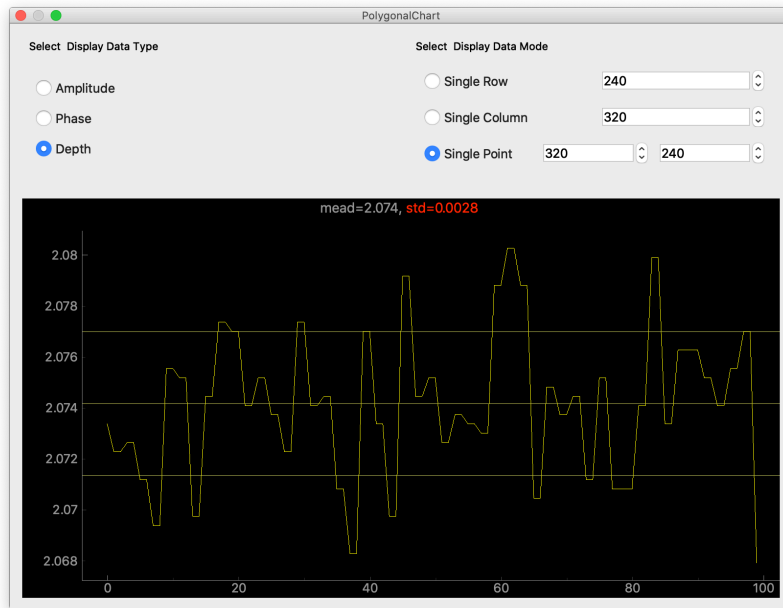
Temporal Noise Chart



Temporal Noise at 4.7 meter



Temporal Noise at 2.0 meter



Note:

The test environment of the above time noise data is indoor, 75% reflectance plate, after 20 minutes of preheating, the integration time is set to 100% (1ms). ,the center point takes 100 consecutive frames of data for statistics.