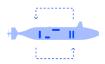


Capture Incredibly Detailed 3D Data

Voyis' Insight Underwater Laser Scanners capture 3D data with submillimeter accuracy to help you see the depths, just like we see the surface. Assets in remote subsea environments can be modelled from a dynamic subsea vehicle or static installation, with all data processed in real-time so that results are immediately available for review.

Benefits & Features



Vehicle Integration

Proven and reliable integration options for subsea vehicles using an easy-to-use software API interface



Real-Time Data

3D data is processed onboard the sensor to deliver real-time actionable data for machine learning



Dynamic Scanning

Proven integration with common navigational sensors enables scanning from moving subsea vehicles



Customer Support

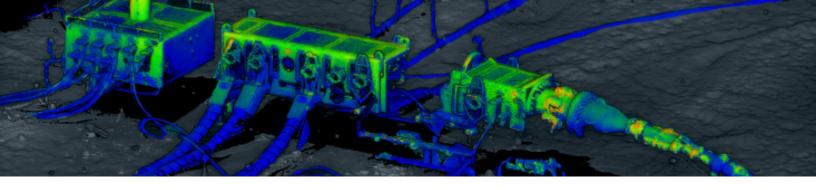
Our team partners with you to find the best solution for your project



Get the Best Data Possible

Sensors that push the limits to deliver the highest resolution, accuracy, and range at any vehicle speed





Find The Right Product For Your Project

Each Insight laser scanner produces high-resolution laser data but there are a few options to best suit your project/deployment.



Insight Nano (formely ULS-100/200)

Compact size for 3D modelling small spaces & short to mid-range targets. Simplified static scanning with embedded actuator.

Depth rating: 1000m

Scan range: 0.13m - 1m & 0.4m - 2.5m (XR)

Points per line: 2064

View All Details



Insight Micro

(formerly ULS-500 Micro)

A long-range laser scanner but in a smaller package making it suitable for small vehicles.

Depth rating: 1000m & 4000m Scan range: 1.2m - 7m

View All Details

Points per line: 2464



Insight Pro

(formerly ULS-500 PRO)

Our longest-range scanner providing the highest quality data possible from larger vehicles.

Depth rating: 4000m & 6000m Scan range: 1.5m - 15m Points per line: 2048

View All Details





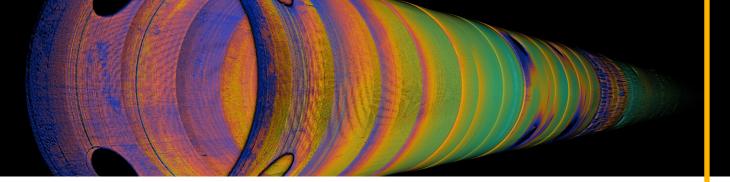
COMPACT LASER SCANNERS

Insight Nano

The Insight Nano is a compact laser scanner designed for straightforward 3D modelling. The integrated actuator and simple user interface enable non-intrusive qualitative inspection without any external aiding sensors.

The system is capable of integration with a variety of deployment vehicles, including small ROVs and pipe crawlers, to deliver high resolution data in confined spaces like pipes, tunnels, and flume tanks.

This new generation Nano is available with time syncronization, dynamic scanning, and high-speed scanning options.



At A Glance

An overview of the main benefits to using an Insight Nano for your project.

- 3D modelling in confinded spaces, in air or water
- Accurate measurements without external sensors
- High-speed rotational or dynamic scanning

Specifications Integration drawings available - <u>contact sales</u>

| opoomou. | To the second se | |
|---|--|--|
| Feature | Nano - Short Range | Nano XR - Medium Range |
| Scan Range* | 0.13m - 1.0m | 0.4m - 2.5m |
| Points Per Line ** | 2064 data points 50° (water) 70° (air) Angle of View | |
| X Resolution (Along laser line) | 0.1mm @ 0.13m 0.3mm @ 0.5m 0.5mm @ 1.0m | 0.2mm @ 0.4m 0.7mm @ 1.5m 1.0mm @ 2.5m |
| Y Resolution (Profile to profile) | 0.05mm @ 0.13m 0.1mm @ 0.5m 0.2mm @ 1.0m | 0.1mm @ 0.4m 0.3mm @ 1.5m 0.5mm @ 2.5m |
| Z Resolution (Depth Resolution) | 0.05mm @ 0.13m 0.1mm @ 0.5m 0.4mm @ 1.0m | 0.05mm @ 0.4m 0.5mm @ 1.5m 1.2mm @ 2.5m |
| Profile Rate | 35 Hz Range limiting option for higher captured rates | |
| Laser 🛕 | Max output: <15mW Pulse duration: 1mSec to CW Wavelength: 450nm or 520nm | WARNING - LASER RADIATION AVOID DIRECT EYE EXPOSURE Class 3R Laser Product |
| Power Consumptio | 25W, 24V | |
| Data Interface | Ethernet, TCP/IP Communication | |
| Depth Rating | 1000m | |
| Data Storage | Topside or Network Storage | |
| Data Acquisition | ViewLS Software C++ API Factory Calibrated Acquisition Modes: Precision Scanning, High-speed Scanning & Dynamic Scanning | |
| Export Data Format | s .XYZ (CSV), LAS Publishing | |
| 3rd Party Integration | on EIVA NaviSuite, QPS QINSy, I | HYPACK HYSWEEP, 4D NAV |
| * Dange measured from C | | alo of view is measured at center of Coan Danas |

^{*} Range measured from Scanner Origin, defined as the center of rotation

^{**} Angle of view is measured at center of Scan Range



