

TF03-180 LiDAR

(Long-range distance sensor)

TF03-180 is an industrial-grade long-range LiDAR. Its maximum detection range can reach 100m. With integrated compensating algorithm for outdoor glare and other interference, TF03-180 can work under strong light environment and rain, fog and snow conditions¹. Multiple built-in operating modes let customers to change its parameters and configuration to meet different applications.

Main product

features

- High frame rate
- IP67 protection
- Small size
- Various interface

Main application

scenarios

- Vehicle collision avoidance and safety warning
- Traffic flow statistics
- Camera trigger
- UAV assisted takeoff and landing



SPECIFICATIONS

Parameters		Standard version	RS485/RS232 version	
Product performance	Operating range	0.1-180m@90% reflectivity		
		0.1-70m@10% reflectivity		
		0.1-130m@90% reflectivity&100Klux		
		0.1-50m@10% reflectivity&100Klux		
	Accuracy ²		±10cm (within 10m), 1%	
			(10m and further)	
	Distance resolution		1cm	



	Frame			1Hz~1000Hz adjustable		
	Frame rate		(default	(default 100Hz)		
	Repeata	ability	1σ: <3cm			
	Ambient ligh	t immunity	100	Klux		
	Operation te	Operation temperature -25~60				
	Enclosure	e rating	IPe	IP67		
	Light source		LD			
Optical	Central wavelength		905	905nm		
parameters	Photobiological safety Cla		Class1 (El	ass1 (EN60825)		
	FOV ⁴ 0.5°		5°			
	Supply voltage		5V~24V			
	Average current		≤150mA @ 5V,≤80mA @			
			12V, ≤50mA @ 24V			
Floctrical	Power consumption		≤1W			
parameters	peak current		150mA			
parameters	Communication interface level		LVTTL(3.3V)	RS485/RS2 32		
	Communication interface		UART/CAN	RS485/RS2 32		
	Dimension		44mm*43mm*32mm(L*W*			
			H)			
Othors	Enclosure material		Aluminum alloy			
Others	Storage temperature		-40~85°C			
	Weight		89g±3g	92g±3g		
	Cable length		70cm			
	UART/RS485/RS232		CAN			
	Baud rate	115200	Baud rate	1000kbps		
Communicatio	Data bit	8	Data bit	0x3003		
n Interface	Stop bit	1	Stop bit	0x3		
in interface	Checksum bit	N/A	Frame format	Standard frame⁵		





1.Rain, snow and fog conditions generally refer to moderate rain, snow and below. Moderate rainfall < 25mm/24h or < 7.9mm/h

2.The detection range is measured at temperature of 25℃. Accuracy and repeatability are measured with white board (90% reflectivity).

3. The highest frame rate can be customized to 10KHz, please contact us for detailed information.

4.FOV, field of view, consists of vertical angle and horizontal angle.

5.Please check Product manual for detailed information.

CONFIGURABLE PARAMETERS

Configurable	Description	Default setting	
parameters			
Frame rate	Output frame rate could be configured	100Hz	
	by related command, range 1~1000Hz ¹	100112	
	UART/CAN can be switched with	d with UART	
Communication	command		
interfaces	RS485/RS232 can be switched with	RS485	
	command		
	a) Serial port baud rate could be		
Paud rate	customized	/	
Bauu late	b) CAN port baud rate could be		
	customized, CAN ID could be modified		
Destore default	TF03-180 can be restored to the factory		
Restore default	settings	/	
	After defining the configuration		
Savo configuration	parameters, you can send the	/	
Save configuration	corresponding command to choose to		
	save the configuration permanently		

Note: for more configurable parameters and instructions, please refer to the user manual.

1. The highest frame rate can be customized to 10KHz, please contact us for detailed information.

WIRING



Since the product upgrade in Aug. 2020, TF03's wiring has also been upgraded.



Figure 2 Wiring of new version TF03-180

Below is new version TF03's pin definition and function description.

No. Color	Standard version		RS485 version		
		PIN definition	Function	PIN definition	Function
1	Red	VCC	Power supply	VCC	Power supply
2	White	CAN_L	CAN_L	RS485-B/RS232-RX	RS485-B/RS232
3	Green	CAN_H	CAN_H	RS485-A/RS232-TX	RS485-A/RS232
4	/	/	/	/	/
5	Blue	UART_RX	UART receive	UART_RX	UART
6	Brown	UART_TX	UART transport	UART_TX	UART
7	Black	GND	Ground	GND	Ground

1.The UART interface of TF03-100 RS485 version is debugging interface. It cannot be used to read detection data.