Zenmuse L1 Known Issues List

Date:	2022.05.11
M300 RTK Firmware:	v04.00.01.11
M300 RTK Remote Controller Firmware:	v04.00.01.10
DJI Pilot 2 App:	v4.0.1.14
Zenmuse L1 Firmware:	v04.00.01.06
DJI Terra:	v3.4.0

NO.	Issue Description	Workaround Solution
1	When the distance between the breakpoint and the previous waypoint (such as the endpoint of the flight route or the elevation change point in Terrain Follow) is less than 30 meters, the point cloud at the breakpoint is occasionally missing.	Optimized in this firmware version to avoid missing point cloud. This issue will be fixed in future versions.
2	When using DJI Terra, the absolute accuracy of the point cloud may decrease in some scenarios after enabling the Optimize Point Cloud Accuracy feature.	Optimize Point Cloud Accuracy is mainly used to improve the relative accuracy of the point cloud model and reduce point cloud layering. This may result in absolute accuracy decreasing in some scenarios. This issue will be fixed in future versions.
3	When using Waypoint mission, if the length of the first or the last flight route segment is less than 30 meters, IMU Calibration will not be available for the flight route with a flight time of more than 100 seconds.	To enable IMU Calibration, adjust the waypoint position of the first or the last flight route segment to make the segment length more than 30 meters. This issue will be fixed in future versions.
4	The point cloud data is layered or missed in the point cloud reconstruction results.	Flights may use the observation data from various base stations. Make sure the distance between the base stations is less than 15 km. It is recommended to use the observation data from the same base station for reconstruction.

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5	The real-time point cloud occasionally shows horizontal or vertical stripes in the point cloud preview.	This point cloud can be displayed as normal in the video transmission view after refreshing, which does not affect the data collection.
6	There is often a small amount of airborne noise in the data collected in rain, fog, or haze.	It is recommended to use a third-party software (such as CloudCompare) to filter out airborne noise. This issue will be fixed in future versions.
7	Color shift occasionally occurs for point cloud coloring. For example, the power lines or the towers were misinterpreted as trees.	This issue will be fixed in future versions.
8	Post-processing modeling could not use the data collected when the aircraft was powered on before takeoff.	This will be supported in future versions.
9	The app prompts "Real-time point cloud transmission unstable. Cannot refresh current point cloud data" and a blank screen occurs in the point cloud view when the video transmission signal is poor. The point clouds can be displayed as normal after the video transmission signal is restored.	It only affects the real-time point cloud display in the app. The point cloud data collection and the post-processing model work as usual.
10	The real-time point clouds beyond the initial point cloud radius of 2 km were not refreshed in the point cloud preview.	It only affects refreshing the real-time point clouds in the point cloud preview. The point cloud data collected and displayed in the video transmission view work as normal.
11	The app occasionally prompted "Load CPU Overload" when using a non-standard SD card.	To avoid missing point cloud data, it is recommended to use one of the high-speed read/write SD cards listed on the L1 Specs page from the DJI official website.
12	After enabling Optimize Point Cloud Accuracy when using DJI Terra, the post-processing speed for data	It is recommended to wait for high-accuracy requirements or disable the Optimize Point Cloud Accuracy feature

	collected in Oblique mission using non-repetitive scan mode is slower than other mission types.	for high-efficiency requirements. This issue will be fixed in future versions.
13.	After the aircraft flies at a constant speed for more than 100 seconds, the absolute accuracy of the point cloud will gradually decrease if the flight speed remains unchanged.	It is recommended that a planned flight at a constant speed should not exceed 100 seconds. For example, the distance between the two neighboring waypoints should not exceed 1 km if the flight speed is set to 10 m/s.

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Date:	2021.05.24	
M300 RTK Firmware:	v02.04.01.02	
M300 RTK Remote Controller Firmware:	v02.04.01.03	
DJI Pilot App Android:	v2.4.1.7	
Zenmuse L1 Firmware:	v02.04.01.08	
DJI Terra:	v3.0.0	

No.	Issue Description	Workaround Solution
1	There is often a small amount of airborne noise in the data collected in rain, fog, or haze.	It is recommended to use a third-party software (such as CloudCompare) to filter out airborne noise. This issue will be fixed in future versions.
2	Color shift occasionally occurs for point cloud coloring. For example, the power lines or the towers were misinterpreted as trees.	This issue will be fixed in future versions.
3	In mapping and aerial photography tasks, the "Terrain Adaptation Flight" and "Calibration Flight" functions cannot be enabled at the same time.	Currently, we recommend performing manual calibration and then enabling Terrain Adaptation Flight. This issue will be fixed in future versions.
4	Post-processing modeling could not use the data collected when the aircraft was powered on before takeoff.	This will be supported in future versions.
5	The app prompts "Real-time point cloud transmission unstable. Cannot refresh current point cloud data" and a blank screen occurs in the point cloud view when the video transmission signal is poor. The point clouds can be displayed as normal after the video transmission signal is restored.	It only affects the real-time point cloud display in the app. The point cloud data collection and the post-processing model work as usual.
6	The real-time point clouds beyond the initial point cloud radius of 2 km were	It only affects refreshing the real-time point clouds in the point cloud preview. The point cloud data collected and

	not refreshed in the point cloud preview.	displayed in the video transmission view work as normal.
7	The app occasionally prompted "Load CPU Overload" when using a non-standard SD card.	To avoid missing point cloud data, it is recommended to use one of the high-speed read/write SD cards listed on the L1 Specs page from the DJI official website.
8	After enabling Optimize Point Cloud Accuracy when using DJI Terra, the post-processing speed for data collected in Oblique mission using non-repetitive scan mode is slower than other mission types.	It is recommended to wait for high-accuracy requirements or disable the Optimize Point Cloud Accuracy feature for high-efficiency requirements. This issue will be fixed in future versions.
9	After the aircraft flies at a constant speed for more than 100 seconds, the absolute accuracy of the point cloud will gradually decrease if the flight speed remains unchanged.	It is recommended that a planned flight at a constant speed should not exceed 100 seconds. For example, the distance between the two neighboring waypoints should not exceed 1 km if the flight speed is set to 10 m/s.