

# USAGE REPORT

Vehicle: SRBC 17

Date: 29/04/2026

Location: SABI AGRI

Missions: 1

## Mission 1

**Trial date** 2026-04-29

**Location** SABI AGRI, Auvergne, France

**Operator** Nicolas

**Start time** 12:30

**End time** 17:09

### Weather

**Precipitation type** None

**Temperature** 24 °C

**Sun position** Zenith

### Terrain

**Slope** 0 %

**Cross slope** 0 %

### Soil

**Texture** Clay loam

**Dominant particle size** Stones 20-200 mm

**Moisture condition** Friable (optimal)

### Crop

**Species** Radis et Carottes

**Growth stage** Maturity

**Weed pressure** 20 %

**Planned operation** Scraping

### Adjacent environment

**Tall vegetation** No

**Tall buildings** No

**Metallic structures** Yes

**Ditch or embankment** Yes

**High voltage lines** No

<b>Roads</b>	No
<b>No network zone</b>	No
<b>Robot configuration</b>	
<b>Robot weight</b>	220 kg
<b>Robot width</b>	0.64 m
<i>Tool</i>	
<b>Tool name</b>	Herse Etri
<b>Tool type</b>	Trailed
<b>Tool weight</b>	15 kg
<b>Tool length</b>	0.6 m
<b>Tool width</b>	0.64 m
<b>Tool height</b>	0.6 m
<b>Tool total length</b>	1.1 m
<b>Working depth</b>	0.08 m



Figure 1.1: Mission presentation photo

## Mission presentation

### Mission parameters

<b>Task to perform</b>	Grattage chardons
<b>Trajectory</b>	Rectiligne, square turn
<b>Working speed</b>	1.8 km/h
<b>Mission file</b>	Interrangboucle03.json

### Organization

<i>Workforce</i>	
<b>Total number of employees</b>	1
<i>Surface</i>	
	0.08 ha

**Theoretical surface of the plot**

**Worked plot surface** 0.0984 ha

**Plot fragmentation** Consolidated (<0.5 km)

**Trajectory**

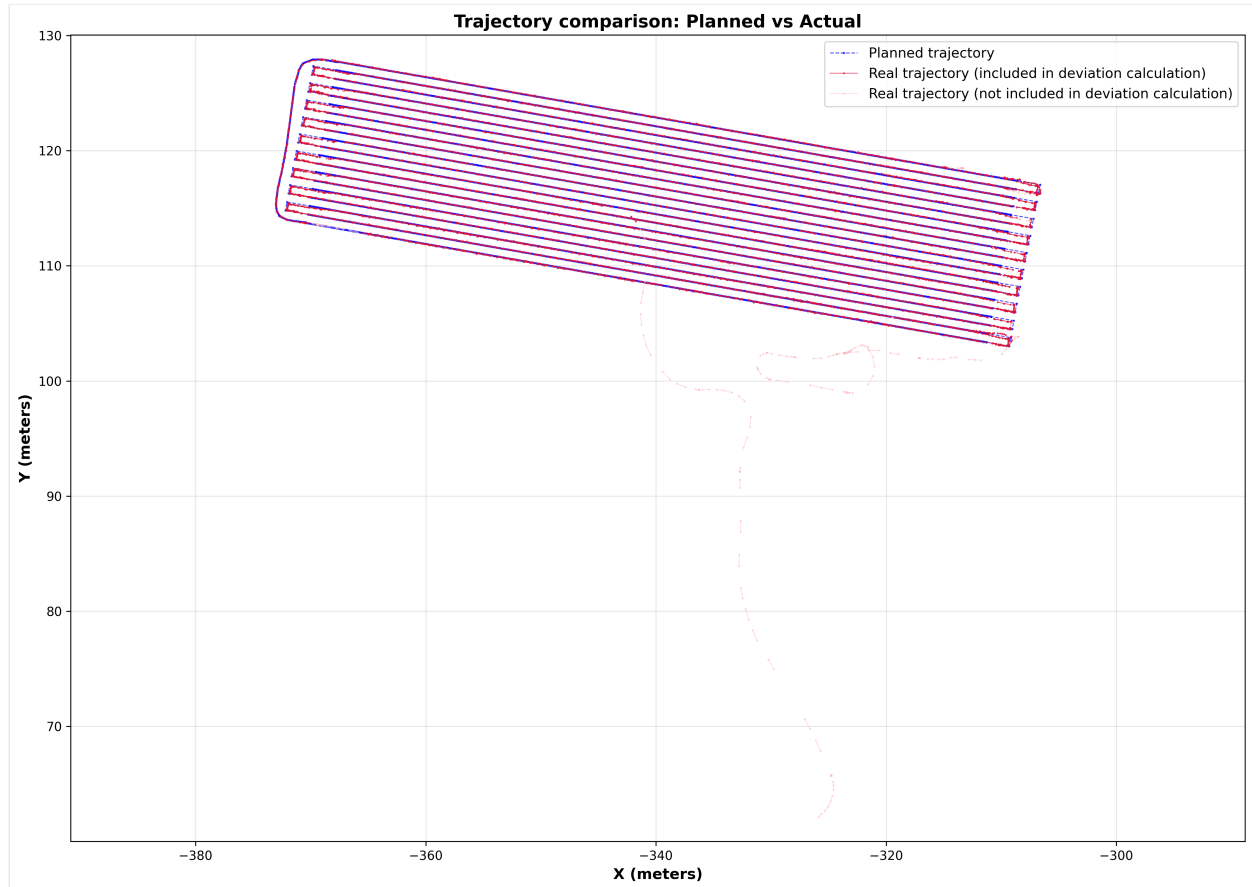


Figure 1.1: Planned vs actual trajectory comparison

**Agronomic Summary**

**Energy per hectare** 5.08 kWh/ha

**Work rate** 0.08 ha/h

**Autonomy per battery** 0.50 ha/batterie

**Time tracking**

**Tool setup** 5 min

**GPS connection wait** 20 min

**Wi-Fi connection wait** 0 min

**Supervision time** 15 min

**Travel time** 5 min

**Restart count** 4

<b>Stop count</b>	4
<b>Stop causes</b>	Perte GPS
<b>Work assessment</b>	
<b>Quality assessment</b>	Neutral
<b>Crop damage</b>	None

**Before work**



**After work**



## Performance Indicators

### Agronomic <sup>[1]</sup>

Indicator	Value	Unit
Crop species	<b>Radis et Carottes</b>	
Growth stage	<b>Maturity</b>	
Soil texture	<b>Clay loam</b>	
Soil moisture	<b>Friable (optimal)</b>	
Weed pressure	<b>20</b>	%
Planned operation	<b>Scraping</b>	
Work quality assessment	<b>Neutral</b>	
Crop damage	<b>None</b>	

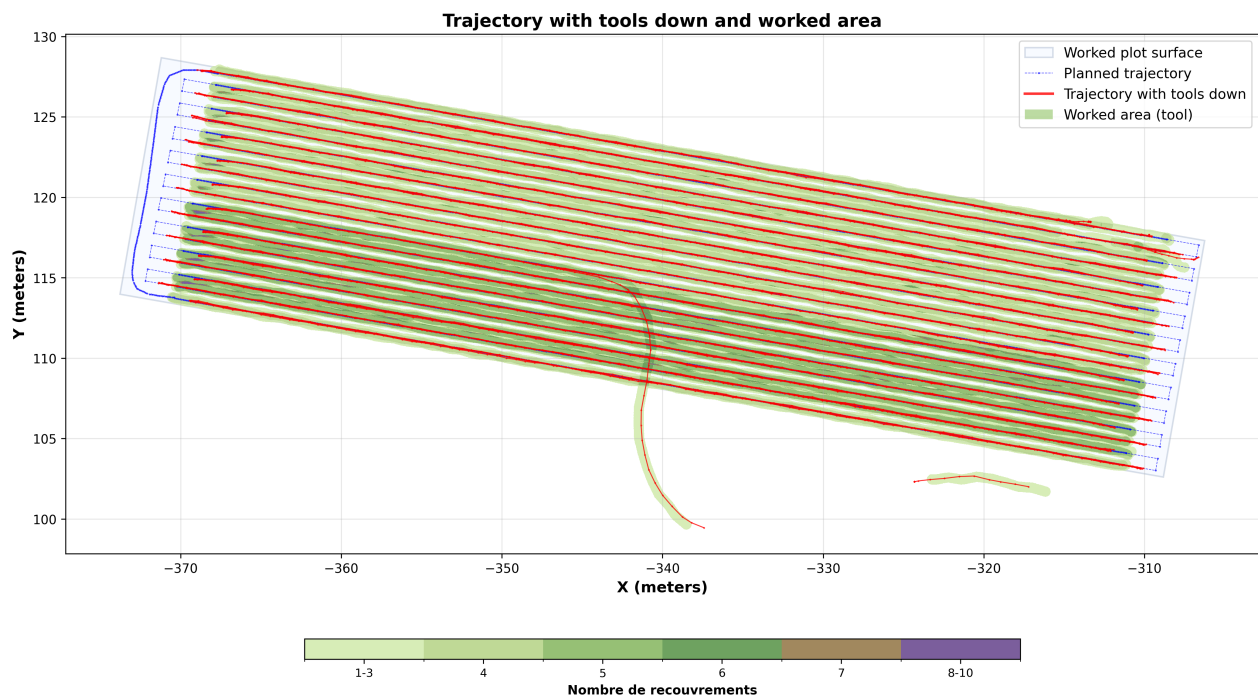
### Energy <sup>[2]</sup>

Indicator	Value	Unit
SOC at start	<b>96.50</b>	%
SOC at end	<b>34.20</b>	%
Total discharge <sup>[3]</sup> <i>For a battery pack capacity of: 2.54 kWh</i>	<b>74.60</b>	%
Total energy consumed	<b>1.90</b>	kWh
Average power	<b>0.41</b>	kW

Indicator	Value	Unit
Energy per hectare	<b>5.08</b>	kWh/ha
Autonomy per battery <i>Reference battery: 2.54 kWh</i>	<b>0.50</b>	ha/batterie

#### Work Rate <sup>[4]</sup>

Indicator	Value	Unit
Work rate <sup>[5]</sup>	<b>0.08</b>	ha/h
Area covered <sup>[6]</sup>	<b>0.37</b>	ha
Worked plot surface <sup>[7]</sup>	<b>0.10</b>	ha
Worked area <sup>[8]</sup>	<b>0.34</b>	ha
Effective area <sup>[9]</sup>	<b>0.09</b>	ha
Coverage rate <sup>[10]</sup>	<b>294.14</b>	%
Average speed (km/h)	<b>1.48</b>	km/h
Max speed (km/h)	<b>3.60</b>	km/h



#### Economic <sup>[11]</sup>

Indicator	Value	Unit
Electricity price	<b>0.19</b>	€/kWh
Labor cost per hour	<b>18.00</b>	€/h
Employees assigned	<b>0</b>	

Indicator	Value	Unit
Labor cost per hectare	0.00	€/ha
Energy cost	0.36	€
Energy cost per hectare	0.97	€/ha
Total cost	0.36	€
Total cost per hectare	0.97	€/ha

### Environmental <sup>[12]</sup>

Indicator	Value	Unit
Temperature	24	°C
Precipitation type	None	
CO <sub>2</sub> emissions <sup>[13]</sup> <i>Emission factor applied: 317 g CO<sub>2</sub> per kWh.</i>	0.60	kg
Plot fragmentation	Consolidated (<0.5 km)	

### Mission <sup>[14]</sup>

Indicator	Value	Unit
Planned distance <sup>[15]</sup>	1308.97	m
Performed distance <sup>[16]</sup>	5836.71	m
Distance deviation	4527.74	m
Performed distance (%)	445.90	%
Mean lateral deviation <i>Without half-turn</i>	3.05	cm
Max lateral deviation <i>Without half-turn</i>	19.83	cm
Mean lateral deviation (tool) <i>Without half-turn, tool distance: 110 cm</i>	5.70	cm
Max lateral deviation (tool) <i>Without half-turn, tool distance: 110 cm</i>	20.00	cm
Worked rows <sup>[17]</sup>	21	

### Operational <sup>[18]</sup>

Indicator	Value	Unit
Robot weight	220.00	kg
Tool weight	15.00	kg
Total weight	235.00	kg

Indicator	Value	Unit
Energy per kg per hectare	<b>0.02</b>	kWh/kg/ha
Mean torque at work (% of nominal) <sup>[19]</sup> <i>Reference nominal torque: 2.39 N·m — Number of motors: 2.</i>	<b>36.24</b>	%

### Safety <sup>[20]</sup>

Indicator	Value	Unit
Geofencing exits	<b>2</b>	
Time outside geofencing (seconds)	<b>1039.46</b>	s
Time outside geofencing (hours)	<b>0.29</b>	h
Local emergency stops	<b>0</b>	
Remote emergency stops	<b>0</b>	
Bumper activations	<b>0</b>	

### Reliability <sup>[21]</sup>

Indicator	Value	Unit
Output errors	<b>0</b>	
Input errors	<b>0</b>	
Battery errors	<b>0</b>	
Motor errors	<b>0</b>	
Cylinder errors	<b>1</b>	
Total errors	<b>1</b>	
Output error time (seconds)	<b>0.00</b>	s
Input error time (seconds)	<b>0.00</b>	s
Battery error time (seconds)	<b>0.00</b>	s
Motor error time (seconds)	<b>0.00</b>	s
Cylinder error time (seconds)	<b>0.06</b>	s
Total error time (seconds)	<b>0.06</b>	s
Error rate per hour	<b>0.21</b>	/h
System availability	<b>100.00</b>	%

### Localization <sup>[22]</sup>

Indicator	Value	Unit
Localization errors	<b>7</b>	
Error time (seconds)	<b>1815.46</b>	s

Indicator	Value	Unit
Error time (hours)	<b>0.50</b>	h

### Time <sup>[23]</sup>

Indicator	Value	Unit
Total duration	<b>16770.50</b>	s
Total duration (hours)	<b>4.66</b>	h
Active time	<b>12028.43</b>	s
Active time (hours)	<b>3.34</b>	h
Inactive time	<b>4742.07</b>	s
Inactive time (hours)	<b>1.32</b>	h
Active time (%)	<b>71.72</b>	%
Inactive time (%)	<b>28.28</b>	%

## Descriptions of indicators

Bracketed numbers refer to definitions, assumptions and sources listed below.

- [1] Agronomic indicator: value from the recorded crop trial context.
- [2] Energy indicator: derived from electrical measurements, consumption and SOC logged during the mission.
- [3] Total discharge (%): energy consumed during the mission (change in cumulative energy, in kWh) divided by nominal battery pack capacity (kWh), multiplied by 100. This indicator does not use start or end SOC; reference pack capacity is stated in the note when known.
- [4] Work-rate indicator: derived from worked areas, speeds and time on field.
- [5] Work rate: amount of work completed per unit of time, in ha/h. Hourly rate = area covered (ha) ÷ total mission duration (h).
- [6] Area covered: this is the area swept by the robot = cumulative odometric distance × robot width.
- [7] Worked plot surface: area of the plot worked by the robot. It is modeled as an oriented bounding box (OBB) with a margin equal to half the robot width around the planned trajectory that was worked.
- [8] Worked area: area processed by the implement (tool width × path length with implement lowered). Each pass counts; overlaps add up.
- [9] Effective area: area worked by the implement excluding overlaps.
- [10] Coverage rate: ratio of worked area to effective area.  $(\text{worked area} - \text{effective area}) / \text{effective area} \times 100$ . A high value indicates many passes over the same zones.
- [11] Economic indicator: computed from cost settings and mission energy/time aggregates.
- [12] Environmental indicator: derived from weather context or consumption using the documented method.
- [13] CO<sub>2</sub> emissions from grid electricity consumed during the mission (kWh × 0.317 kg/kWh). Source: French Ministry for Ecological Transition — Key Climate Figures (digital edition), chapter on GHG emissions from industry / electricity production ([statistiques.developpement-durable.gouv.fr](https://statistiques.developpement-durable.gouv.fr)).
- [14] Mission indicator: derived from actual path, plan and computed geometric deviations.
- [15] Theoretical mission distance: cumulative length of the planned trajectory from the mission JSON file. Does not match the robot's actual path.
- [16] Distance actually traveled by the robot. May include movement before the mission effectively starts and after it ends, depending on the recorded data.
- [17] Number of distinct rows worked (tool lowered).
- [18] Operational indicator: derived from kinematics, implement data or documented masses.
- [19] Mean absolute motor torque only when the tool is lowered, as a percentage of the motors' nominal torque.
- [20] Safety indicator: derived from safety-related events and durations.
- [21] Reliability indicator: derived from fault codes and error time per subsystem.
- [22] Localization indicator: derived from localization faults or downtime during the mission.
- [23] Time indicator: derived from timestamps and activity states during the mission.