

USAGE REPORT

Vehicle: SRBC TEST
Location: Toulouse Gofar

Date: 04/02/2026
Missions: 1

Mission 1

Trial date 2026-02-04

Location Toulouse, Occitanie, France

Operator Nicolas

Start time 16:55

End time 18:02

Weather

Precipitation type None

Temperature 10 °C

Sun position Couché

Terrain

Slope 0 %

Cross slope 0 %

Soil

Texture Sandy clay

Dominant particle size Gravel 2-20 mm

Moisture condition Very wet (plastic)

Crop

Species Radish

Growth stage Soil preparation

Weed pressure 3 %

Planned operation Soil preparation

Adjacent environment

Tall vegetation Yes

Tall buildings No

Metallic structures No

Ditch or embankment Yes

High voltage lines No

Roads	Yes
No network zone	No
Robot configuration	
Robot weight	280 kg
Robot width	0.64 m
<i>Tool</i>	
Tool name	Bineuse
Tool type	Mounted
Tool weight	30 kg
Tool length	0.8 m
Tool width	0.6 m
Tool height	0.6 m
Tool total length	0.8 m
Working depth	0.05 m



Figure 1.1: Mission presentation photo

Mission presentation

Mission parameters

Task to perform	Binage
Trajectory	rectiligne,U turn
Working speed	1.5 km/h
Mission file	2026-02-04T16_36_36.json

Organization

<i>Workforce</i>	
Total number of employees	1
Employees on robot task	0
<i>Surface</i>	
	0.01 ha

Theoretical surface of the plot

Plot fragmentation Consolidated (<0.5 km)

Agronomic Summary

Work rate N/A

Time tracking

Tool setup	10 min
GPS connection wait	60 min
Wi-Fi connection wait	20 min
Supervision time	180 min
Travel time	60 min
Restart count	4
Stop count	8
Stop causes	Derive de rang (écrasement de la culture); Arrêt demis-tour; Perte GPS RTK; Perte Wifi

Work assessment

Quality assessment	Dissatisfied
Crop damage	Medium (10 m)

Performance Indicators

Agronomic ^[1]

Indicateur	Valeur	Unité
Crop species	Radish	
Growth stage	Soil preparation	
Soil texture	Sandy clay	
Soil moisture	Very wet (plastic)	
Weed pressure	3	%
Planned operation	Soil preparation	
Work quality assessment	Dissatisfied	
Crop damage	Medium (10 m)	

Energy ^[2]

Indicateur	Valeur	Unité
SOC at start	82.90	%

Indicateur	Valeur	Unité
SOC at end	77.40	%
Total discharge ^[3] <i>No consumption data available</i>	<i>N/A</i>	%

Work Rate ^[4]

Indicateur	Valeur	Unité
Work rate ^[5]	<i>N/A</i>	ha/h
Area covered ^[6]	<i>N/A</i>	ha
Worked plot surface ^[7]	<i>N/A</i>	ha
Worked area ^[8]	<i>N/A</i>	ha
Effective area ^[9]	<i>N/A</i>	ha
Coverage rate ^[10]	<i>N/A</i>	%
Average speed (km/h)	0.85	km/h
Max speed (km/h)	1.98	km/h

Economic ^[11]

Indicateur	Valeur	Unité
Electricity price	<i>N/A</i>	€/kWh
Labor cost per hour	<i>N/A</i>	€/h
Employees assigned	0	
Labor cost per hectare	<i>N/A</i>	€/ha
Energy cost	<i>N/A</i>	€
Energy cost per hectare	<i>N/A</i>	€/ha
Total cost <i>Prix de l'électricité non disponible dans le COD</i>	<i>N/A</i>	€
Total cost per hectare	<i>N/A</i>	€/ha

Environmental ^[12]

Indicateur	Valeur	Unité
Temperature	10	°C
Precipitation type	None	
CO ₂ emissions ^[13] <i>Emission factor applied: 317 g CO₂ per kWh.</i>	<i>N/A</i>	kg
Plot fragmentation	Consolidated (<0.5 km)	

Mission ^[14]

Indicateur	Valeur	Unité
Planned distance ^[15]	<i>N/A</i>	m
Performed distance ^[16]	0.00	m
Distance deviation	<i>N/A</i>	m
Performed distance (%)	<i>N/A</i>	%
Mean lateral deviation <i>Without half-turn</i>	<i>N/A</i>	cm
Max lateral deviation <i>Without half-turn</i>	<i>N/A</i>	cm
Mean lateral deviation (tool) <i>Without half-turn, tool distance: 80 cm</i>	<i>N/A</i>	cm
Max lateral deviation (tool) <i>Without half-turn, tool distance: 80 cm</i>	<i>N/A</i>	cm
Worked rows ^[17]	<i>N/A</i>	

Operational ^[18]

Indicateur	Valeur	Unité
Robot weight	280.00	kg
Tool weight	<i>N/A</i>	kg
Total weight	280.00	kg
Energy per kg per hectare	<i>N/A</i>	kWh/kg/ha
Mean torque at work (% of nominal) ^[19] <i>Reference nominal torque: 2.39 N·m — Number of motors: 2.</i>	49.47	%

Safety ^[20]

Indicateur	Valeur	Unité
Geofencing exits	0	
Time outside geofencing (seconds)	<i>N/A</i>	s
Time outside geofencing (hours)	<i>N/A</i>	h
Local emergency stops	0	
Remote emergency stops	0	
Bumper activations	0	

Reliability ^[21]

Indicateur	Valeur	Unité
Output errors	0	
Input errors	0	
Battery errors	0	
Motor errors	0	
Cylinder errors	0	
Total errors	0	
Output error time (seconds)	N/A	s
Input error time (seconds)	N/A	s
Battery error time (seconds)	N/A	s
Motor error time (seconds)	0.00	s
Cylinder error time (seconds)	N/A	s
Total error time (seconds)	0.00	s
Error rate per hour	0.00	/h
System availability	100.00	%

Localization ^[22]

Indicateur	Valeur	Unité
Localization errors	0	
Error time (seconds)	N/A	s
Error time (hours)	N/A	h

Time ^[23]

Indicateur	Valeur	Unité
Total duration	3850.42	s
Total duration (hours)	1.07	h
Active time	961.72	s
Active time (hours)	0.27	h
Inactive time	2888.70	s
Inactive time (hours)	0.80	h
Active time (%)	24.98	%
Inactive time (%)	75.02	%

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] CO₂ 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).
- [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.