USAGE REPORT

Vehicle:	SRBC TEST	**Date:**	17/03/2026
Location:	SABI AGRI	**Missions:**	1

Mission 1

Trial date	2026-03-17
Location	SABI AGRI, Auvergne, France
Operator	Nicolas
Start time	10:15
End time	17:24
Weather	
Precipitation type	None
Temperature	17 °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	Carottes et Radis
Growth stage	Emergence
Weed pressure	5 %
Planned operation	Scraping
Adjacent environment	
Tall vegetation	No
Tall buildings	No
Metallic structures	Yes
Ditch or embankment	Yes
High voltage lines	No

Roads	No
No network zone	No
Robot configuration	
Robot weight	280 kg
Robot width	0.64 m
Tool	
Tool name	Herse Etri
Tool type	Trailed
Tool weight	15 kg
Tool length	0.8 m
Tool width	0.6 m
Tool height	0.6 m
Tool total length	1.1 m
Working depth	0.07 m

Figure 1.1: Mission presentation photo

Mission presentation

Mission parameters

Task to perform	Grattage
Trajectory	Rectiligne, square turn, Boucle
Working speed	3 km/h
Mission file	mission_complete_inter_rang_boucle.json
Organization	
Workforce	
Total number of employees	1
Surface	
	0.08 ha

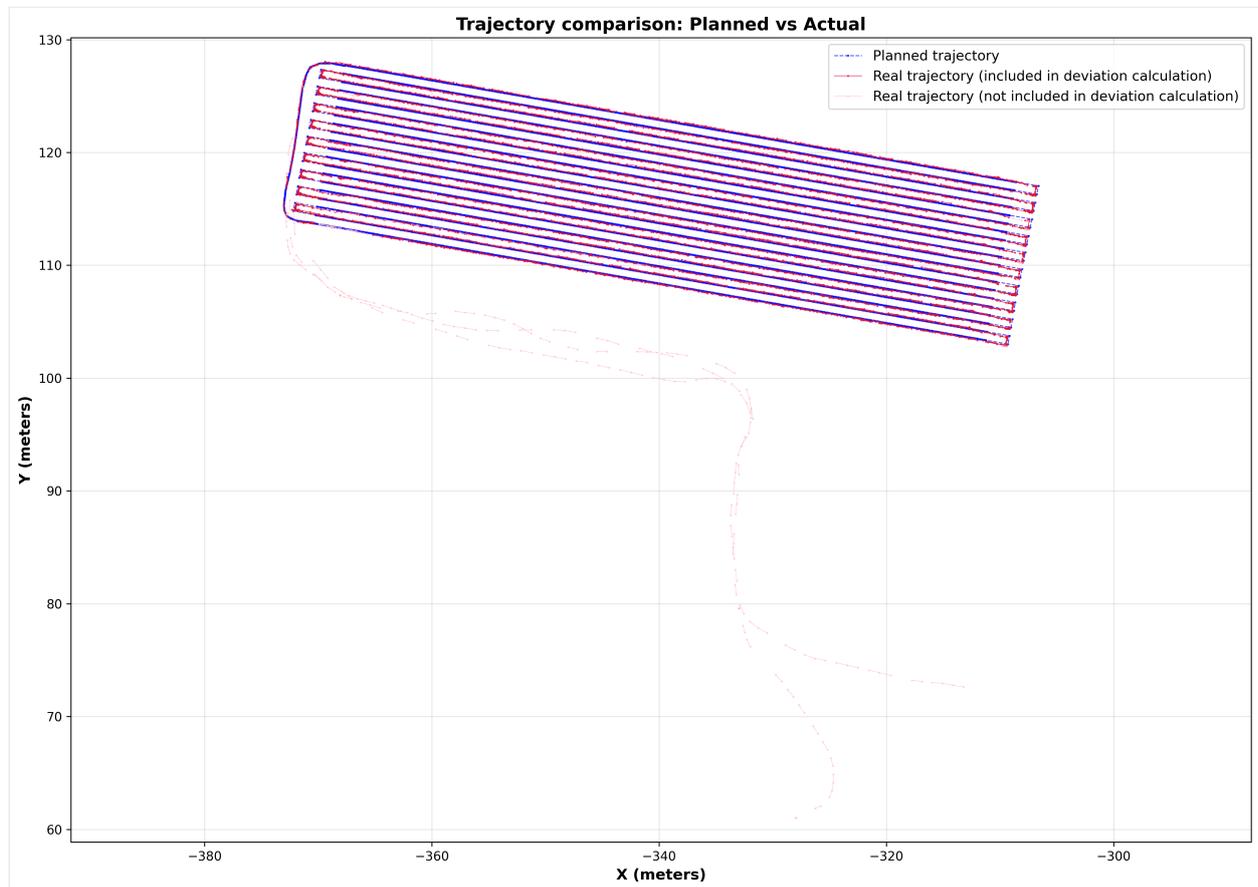|	
Theoretical surface of the plot	
Worked plot surface	0.0984 ha
Plot fragmentation	Consolidated (<0.5 km)

Trajectory

Figure 1.1: Planned vs actual trajectory comparison

Agronomic Summary

Energy per hectare	5.93 kWh/ha
Work rate	0.05 ha/h
Autonomy per battery	0.43 ha/batterie

Time tracking

Tool setup	0 min
GPS connection wait	10 min
Wi-Fi connection wait	40 min
Supervision time	20 min
Travel time	10 min
Restart count	1

Stop count	1	
Stop causes	Faut positif caméra; Coupure GPS, Upload des bags trop gros. Bags des images caméra enlevés. 2Mo à la place de 45Mo à upload. ça semble être bien mieux	

Work assessment

Quality assessment	Neutral
Crop damage	Low

Before work	After work

Performance Indicators

Agronomic [1]

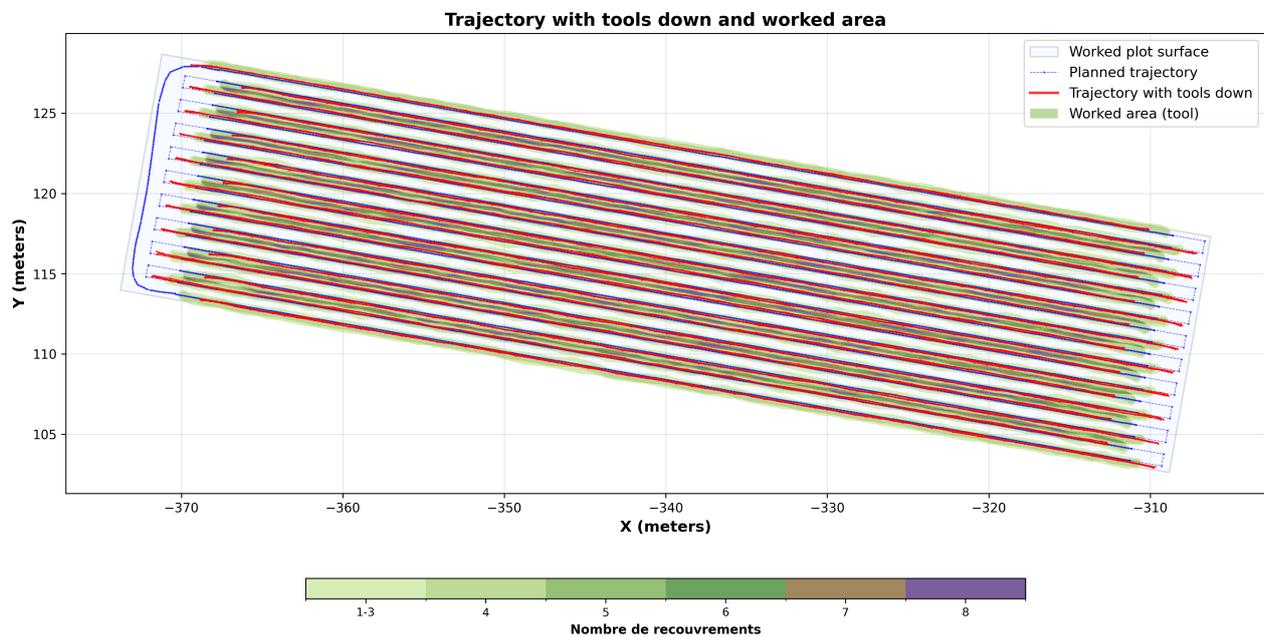| Indicateur	Valeur	Unité
Crop species	Carottes et Radis	
Growth stage	Emergence	
Soil texture	Clay loam	
Soil moisture	Friable (optimal)	
Weed pressure	5	%
Planned operation	Scraping	
Work quality assessment	Neutral	
Crop damage	Low	

Energy [2]

Indicateur	Valeur	Unité
SOC at start	62.70	%
SOC at end	63.60	%
Total discharge [3] *For a battery pack capacity of: 2.54 kWh*	82.12	%
Total energy consumed	2.09	kWh

Indicateur	Valeur	Unité
Average power	0.29	kW
Energy per hectare	5.93	kWh/ha
Autonomy per battery *Reference battery: 2.54 kWh*	0.43	ha/batterie

Work Rate [4]

Indicateur	Valeur	Unité
Work rate [5]	0.05	ha/h
Area covered [6]	0.35	ha
Worked plot surface [7]	0.10	ha
Worked area [8]	0.29	ha
Effective area [9]	0.07	ha
Coverage rate [10]	299.65	%
Average speed (km/h)	1.83	km/h
Max speed (km/h)	3.60	km/h

Trajectory with tools down and worked area

Legend: Worked plot surface, Planned trajectory, Trajectory with tools down, Worked area (tool)

Nombre de recouvrements: 1-3, 4, 5, 6, 7, 8

Economic [11]

Indicateur	Valeur	Unité
Electricity price	0.19	€/kWh
Labor cost per hour	18.00	€/h
Employees assigned	0	

Indicateur	Valeur	Unité
Labor cost per hectare	0.00	€/ha
Energy cost	0.40	€
Energy cost per hectare	1.13	€/ha
Total cost	0.40	€
Total cost per hectare	1.13	€/ha

Environmental [12]

Indicateur	Valeur	Unité
Temperature	17	°C
Precipitation type	None	
CO_2 emissions [13] *Emission factor applied: 317 g CO_2 per kWh.*	0.66	kg
Plot fragmentation	Consolidated (<0.5 km)	

Mission [14]

Indicateur	Valeur	Unité
Planned distance [15]	1308.97	m
Performed distance [16]	5503.58	m
Distance deviation	4194.60	m
Performed distance (%)	420.45	%
Mean lateral deviation *Without half-turn*	9.31	cm
Max lateral deviation *Without half-turn*	19.93	cm
Mean lateral deviation (tool) *Without half-turn, tool distance: 110 cm*	11.16	cm
Max lateral deviation (tool) *Without half-turn, tool distance: 110 cm*	20.00	cm
Worked rows [17]	21	

Operational [18]

Indicateur	Valeur	Unité
Robot weight	280.00	kg
Tool weight	15.00	kg
Total weight	295.00	kg

Indicateur	Valeur	Unité
Energy per kg per hectare	0.02	kWh/kg/ha
Mean torque at work (% of nominal) [19] *Reference nominal torque: 2.39 N·m — Number of motors: 2.*	48.37	%

Safety [20]

Indicateur	Valeur	Unité
Geofencing exits	1	
Time outside geofencing (seconds)	48.00	s
Time outside geofencing (hours)	0.01	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)	0.00	s
Input error time (seconds)	0.00	s
Battery error time (seconds)	0.00	s
Motor error time (seconds)	0.00	s
Cylinder error time (seconds)	0.00	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	8	
Error time (seconds)	7329.92	s

Indicateur	Valeur	Unité
Error time (hours)	2.04	h

Time [23]

Indicateur	Valeur	Unité
Total duration	25715.24	s
Total duration (hours)	7.14	h
Active time	8867.77	s
Active time (hours)	2.46	h
Inactive time	16847.46	s
Inactive time (hours)	4.68	h
Active time (%)	34.48	%
Inactive time (%)	65.52	%

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. (worked area − effective area) / effective area × 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_2 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.

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