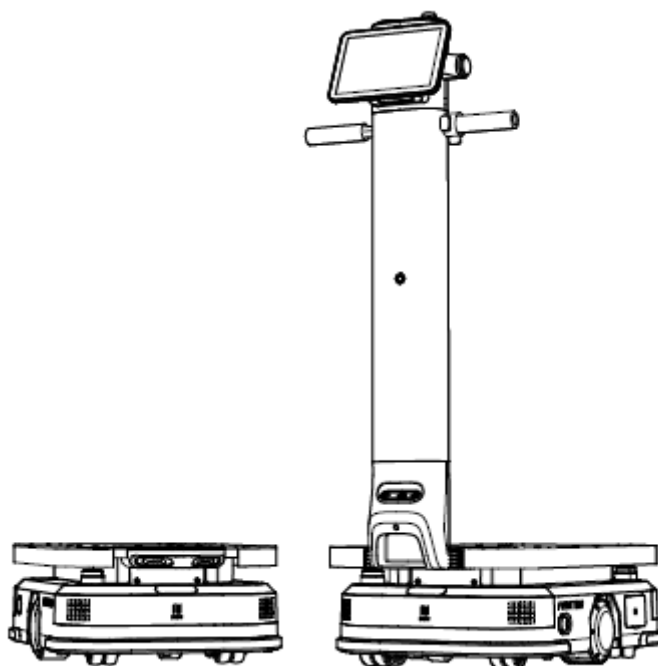




# PUDU T600 Operation Guide

Version: V1.1.1

Model: WTIDL2 WTIDU2

Shenzhen Pudu Technology Co., Ltd.



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## Introduction

### Purpose

This manual describes the usage precautions, the functions, technical specifications, and detailed operations, daily maintenance of PUDU T600 to help users better understand and work with the robot.

### Signs

The signs listed below may appear in this manual with the following meanings.

| Sign                                                                                      | Description                                                                                                          |
|-------------------------------------------------------------------------------------------|----------------------------------------------------------------------------------------------------------------------|
|  Danger  | Indicates high potential hazards, which could cause death or serious personal injury if not avoided.                 |
|  Warning | Indicates moderate or low potential hazards, which could cause minor personal injury or robot damage if not avoided. |
|  Caution | Indicates potential risks, which could cause robot damage, data loss, or unpredictable consequences if neglected.    |
| & Note                                                                                    | Provides additional information as the emphasis and supplement to the main text.                                     |



Please keep this manual in a safe place, as it contains important safety and operating instructions.

Operator must complete training and read this manual before using the robot..

### Changelog

| Version | Release Date | Description                                                                                            |
|---------|--------------|--------------------------------------------------------------------------------------------------------|
| v1.0.0  | 2025/10/31   | Initial version                                                                                        |
| v1.0.1  | 2025/11/19   | Add Conterweight-Towing Load Relationship                                                              |
| v1.0.2  | 2025/12/22   | Add Instructions on Load Center of Gravity                                                             |
| v1.1.0  | 2026/02/24   | Add section: Task creation methods.<br>Provide imperial unit conversion for non-configurable items.    |
| v1.1.1  | 2026/04/17   | Added the specification table for the relationship between carried cargo dimensions and load capacity. |



PUDU

## PUDU T600 Operation Guide



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# 1. Safety Instructions

## 1.1 Electrical Requirements

- Charge the robot using the charger delivered with it. Do not use other chargers. If the charger is damaged, replace it in a timely manner.
- Please charge the battery to 100% before first use.
- When the battery is lower than 20%, charge the robot in a timely manner. Do not run the robot with a low battery for a long time. The battery life may be reduced.
- Make sure that the power supply voltage complies with the voltage range specified on the charger, otherwise the charger may be damaged.
- Do not drop the charger or hit it. Otherwise, damage to the charger may be caused.
- Please dispose of the battery according to local regulations and do not dispose of it as household waste. Improper handling may cause the battery to explode.

## 1.2 Use Requirements

- Do not block the robot sensor. Otherwise, the robot may fail to move properly or get lost.
- Cleaning or maintenance work is prohibited while the robot is powered on.
- Do not pick up or place any items while the robot is moving, to avoid property losses or personal injury caused by accidental collisions.
- Do not push or carry the robot while it is moving, to prevent it from running abnormally.
- Do not touch the robot when the drive wheels, lifting mechanisms, towing devices, or other moving parts are in operation.
- The robot can be disassembled or repaired only by trained professionals. In case of any fault with the robot, please contact a technical support engineer immediately.
- When moving the robot, please observe the requirements on the maximum allowed weight for a single person stipulated by local laws or regulations. While the robot is being moved, please be sure to always keep it in an upright position.
- When the robot is in motion, no playing is allowed in front of the robot to avoid unnecessary harm.
- Although the robot features automatic obstacle avoidance, never block the robot moving at a high speed to avoid any accidents.
- Please prevent the robot from violent impact or shock to avoid any damage.
- Do not clean the robot with caustic chemicals, cleansers, or detergents. Always clean the robot by wiping it with a clean and dry cloth.
- In case of an emergency while the robot is in motion, please press the emergency stop button located at the top to stop the robot.
- Do not spill any liquids inside the robot to prevent damage.
- If the collision sensors are impacted while the robot is moving, the robot will stop and pause the task. At this point, you can follow the on-screen instructions to resume the task.

## 1.3 Environmental Requirements

- Do not use or charge the robot in dangerous environments with high temperature, high pressure, or risks of flames or explosions, so as to avoid personal injury or damage to the product.
- Do not use the robot in a humid environment or in the presence of liquid or viscous substances on the ground, so as to avoid damage to the robot.
- Do not use the robot in locations where wireless devices are explicitly prohibited, as this may interfere with other electronic devices or cause other hazards.
- Do not use the robot in a humid environment or on surfaces covered with fluid or gooeey stuff to avoid damage to the robot.
- This robot is suitable for use on dry, flat surfaces. It is not suitable for use in slippery environments, environments with steps, steep slopes. If the robot gets stuck in a pit, please push the robot's chassis to help it get out. Please do not forcefully pull or push the handle.
- It is necessary to use the robot under the product operating environment declared in this manual. Otherwise, there may be abnormal operation of the equipment or other hazards.
- Do not dispose of the robot and its accessories as ordinary domestic waste. Please comply with local regulations on the disposal of the robot and its accessories and support recycling.

## 1.4 Intended Use

The PUDU T600 Series is a delivery robot designed for heavy-payload material transport scenarios such as industrial and warehouse environments. With a maximum load capacity of 600 kg (1322.77 pounds), it is equipped with fundamental IoT capabilities. The product offers extensive software and hardware interfaces for seamless system integration and hardware expansion. Centered around a robust load-bearing chassis, this series emphasizes high compatibility and openness, and comprises two models:

- The standard version, featuring an operation screen and push handle for user-friendly interaction;
- The override version, designed as a pure chassis that can navigate underneath racks for enhanced flexibility.

## 1.5 Foreseeable Misuse

Any application of the PUDU T600 in situations inconsistent with its intended use is considered misuse. This includes but is not limited to:

- Exceeding the robot's maximum load capacity.
- Placing loads in a manner that does not conform to the load distribution stated in the manual.
- Using the robot to transport people.
- Modifying the robot's hardware configuration without training or permission.
- Using the robot in scenarios that do not comply with those stated in the manual.
- Utilizing safety components such as the collision switch, emergency stop switch, and obstacle avoidance sensors for other purposes.

## 1.6 User

Users must receive the necessary training related to the tasks they are expected to perform

before using the PUDU T600. Based on the actual application and maintenance scenarios of the robot, users can be categorized into three main types: Debugging Personnel, Maintenance Personnel, General Users and Indirect Users . The responsibilities of each type of user are as follows:

#### (1) Debugging Personnel

Responsible for assessing the risks associated with the robot's operating environment. Based on actual environmental conditions, they should make appropriate modifications to ensure the safe and reliable operation of the robot. Specific tasks include:

- Product operation debugging, including mapping and robot parameter configuration.
- Installing and removing modules that need to be permanently mounted on the robot.
- Conducting necessary safety tests for robot operation in specific scenarios.

#### (2) Maintenance Personnel

Responsible for the routine upkeep and maintenance of the robot. They also create and modify maps when the robot's operating environment changes. Specific tasks include:

- Maintaining and servicing the robot.
- Creating or modifying the robot's map and conducting necessary operational testing.
- Creating or modifying robot tasks.

#### (3) General Users

General users of the robot should familiarize themselves with the relevant safety precautions outlined in this document and utilize the basic functions of the robot. Specific tasks include:

- Sending tasks to the robot.
- Loading or unloading goods onto or from the robot.

#### (4) Indirect Users

Personnel who do not directly operate the robot are considered indirect users. The users of the robot must clearly inform indirect users of the necessary safety precautions during the robot's operation.



Caution

General Users and Indirect User are prohibited from maintaining equipment.

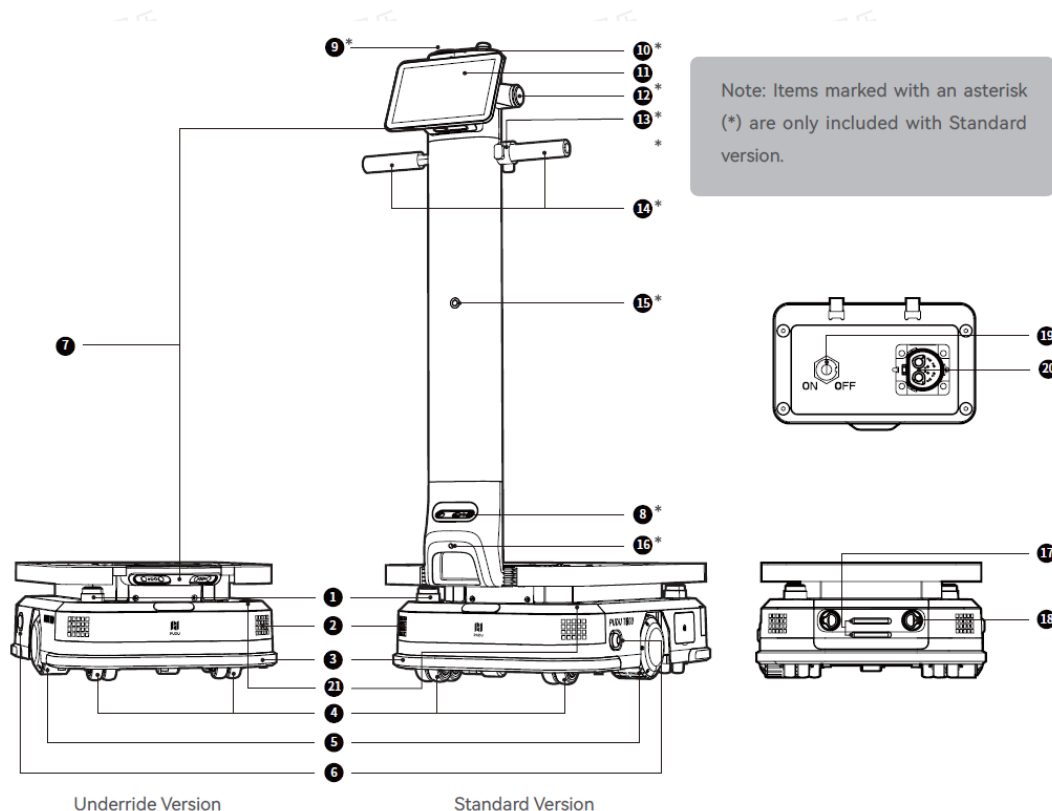
## 2. Product Introduction

### 2.1 Overview

The PUDU T600 Series is a delivery robot designed for heavy-payload material transport scenarios such as industrial and warehouse environments. With a maximum load capacity of 600 kg, it is equipped with fundamental IoT capabilities. The product offers extensive software and hardware interfaces for seamless system integration and hardware expansion. Centered around a robust load-bearing chassis, this series emphasizes high compatibility and openness, and comprises two models:

- The standard version, featuring an operation screen and push handle for user-friendly interaction;
- The underride version, designed as a pure chassis that can navigate underneath racks for enhanced flexibility.

### 2.2 Appearance & Components



| No. | Description             |
|-----|-------------------------|
| 1   | Lidar                   |
| 2   | Chassis indicator light |
| 3   | Collision sensor        |
| 4   | Auxiliary wheels        |
| 5   | Drive wheels            |



|     |                          |
|-----|--------------------------|
| 6   | Emergency stop switch    |
| 7   | Downward RGBD            |
| 8*  | Upward RGBD              |
| 9*  | Top view camera          |
| 10* | Top indicator light      |
| 11* | LCD screen               |
| 12* | Shortcut button          |
| 13* | Power-assist switch      |
| 14* | Handles                  |
| 15* | Front view camera        |
| 16* | Safety contour projector |
| 17  | Battery box              |
| 18  | Charging electrode plate |
| 19  | Brake switch             |
| 20  | Charging port            |
| 21  | Power switch             |

### 2.3 Technical specifications

| Product Feature    | Description                                                                    |                                                                                                   |
|--------------------|--------------------------------------------------------------------------------|---------------------------------------------------------------------------------------------------|
| Model              | Standard Version: WTIDL2<br>Underride Version: WTIDU2                          |                                                                                                   |
| Overall dimensions | Standard version: 960 x 500 x 1350 mm<br>Underride version: 845 x 500 x 255 mm | Standard version: 37.80 x 19.69 x 53.15 inches<br>Underride version: 33.27 x 19.69 x 10.04 inches |
| Overall weight     | Standard version: 112 kg<br>Underride version: 94 kg                           | Standard version: 246.92 pounds<br>Underride version: 207.23 pounds                               |
| Operating voltage  | DC 20.8 V~29.2 V                                                               |                                                                                                   |
| Battery capacity   | 30 Ah                                                                          |                                                                                                   |
| Max. load          | 600 kg                                                                         | 1322.77 pounds                                                                                    |
| Charging time      | About 2 h (from 0 % to 90 %)                                                   |                                                                                                   |
| Battery life       | 12 h (None load); 6 h (Max. load)                                              |                                                                                                   |



|                           |                                                               |                                                                   |
|---------------------------|---------------------------------------------------------------|-------------------------------------------------------------------|
| Screen specifications     | Standard version: 10.1" LCD screen<br>Underride version: None |                                                                   |
| Navigation Method         | Standard version: VSLAM + LSLAM<br>Underride version: LSLAM   |                                                                   |
| Min. Path Clearance       | Standard version: 70 cm<br>Underride version: 65 cm           | Standard version: 27.56 inches<br>Underride version: 25.59 inches |
| Max. surmountable height  | 10 mm                                                         | 0.39 inch                                                         |
| Max surmountable gap      | 35 mm                                                         | 1.38 inches                                                       |
| Speed                     | 0.2–1.2 m/s, adjustable                                       | 0.66-3.94 ft/s, adjustable                                        |
| Operating system          | Android                                                       |                                                                   |
| Speaker power             | 10 W × 2 stereo speaker                                       |                                                                   |
| Working environment       | Temperature: 0 °C to 40 °C; humidity: ≤ 85% RH                |                                                                   |
| Storage environment       | Temperature: -20 °C to 60 °C; humidity: ≤ 85% RH              |                                                                   |
| Operating altitude        | < 2000 m                                                      | < 6561.68 ft                                                      |
| Road surface requirements | Indoor environment with flat, smooth surfaces                 |                                                                   |
| Charger power input       | AC 100 V~240 V, 50/60 Hz                                      |                                                                   |
| Charger power output      | 29.2 V, 15 A                                                  |                                                                   |

### 3. Battery and Charging

The PUDU T600 is powered by a quick-swappable lithium battery, which can be charged using the included wired charger or a charging dock. It also supports rapid battery replacement while in operation. When the battery is removed, the robot will remain powered on for 60 seconds, allowing sufficient time to install a new battery within the power supply window.

#### 3.1 To Charge the Robot

##### ⚠Caution

Before using the robot for the first time, it is necessary to fully charge the robot's battery to 100%..

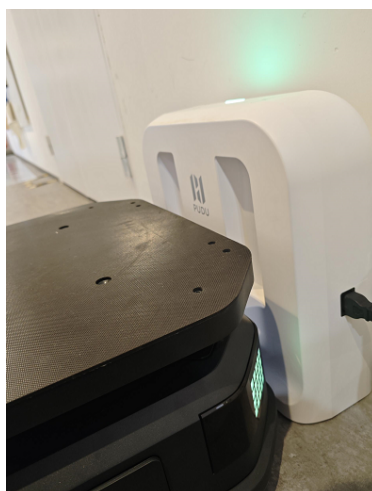
If the robot has not been used for more than a month, it is also necessary to fully charge the battery to 100% before using it again.

The robot supports charging using both a charger and a charging pile.

a) Charging with charger: Simply insert the provided charger into the robot's charging port to start the charging process.



b) Charging with a charging pile: After deploying the charging pile according to the instructions, power on the robot. On the robot's home page interface, click the "Charge Now" button to initiate automatic charging.



#### 3.2 Battery Replacement

In addition to recharging the robot's battery, it is also possible to directly replace the battery. The specific steps are as follows:

Step 1 With the robot powered off, use both hands to pull the battery compartment cover tab and remove the battery compartment cover.

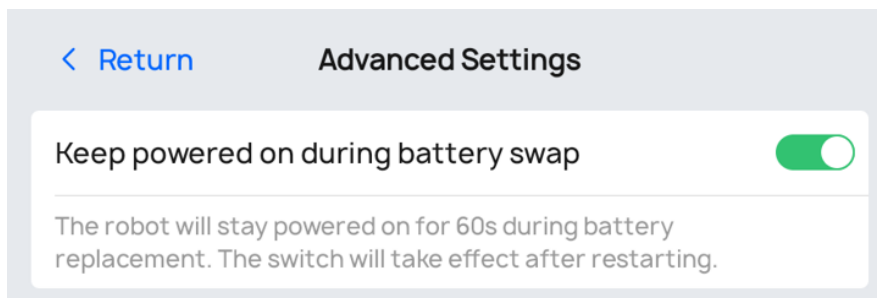


Step 2 Disconnect the power connector attached to the battery and remove the battery from the robot. Replace it with a new battery.



Step 3 After replacing the battery, connect the power connector and cover the battery compartment. The robot can now be powered on and used.

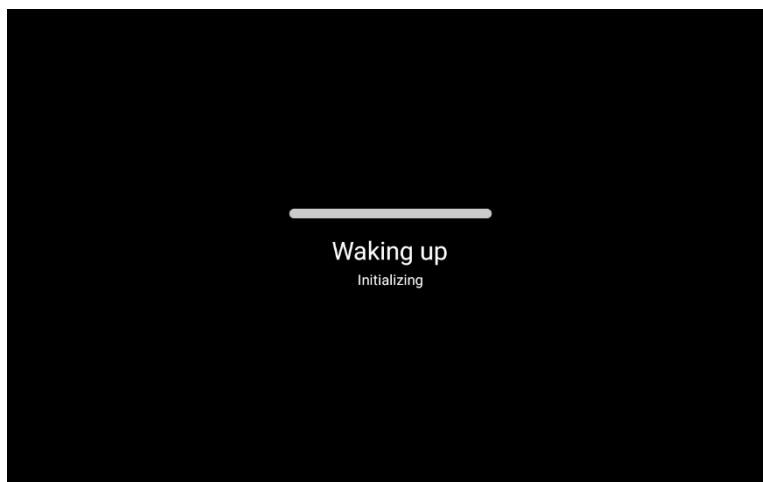
When the battery is removed while the robot is powered on, it will maintain its power-on status for 60 seconds. If the battery swap is completed during this period, the robot will not power off. This avoids the repetitive power-on action when replacing the battery, improving battery swap efficiency.



Step 1 Enable the “Keep Power On During Battery swap” switch in “Settings” - “Advanced Settings.”.

Step 2 When the robot is powered on and the battery cover is removed, the robot will enter a low power state. At this time:

- The robot's screen will turn off
- The chassis logo light will remain lit



Step 3 After replacing the battery, connect the power connector and cover the battery compartment. The robot can now be powered on and used.

#### △Note

- If the battery swap (i.e., covering the battery compartment) is completed within 60 seconds, the robot will wake up approximately 5 seconds later and return to normal operating status.
- If the battery swap is not completed within 60 seconds, the robot will automatically shut down.

### 3.3 Battery Storage

When the battery is removed for independent charging, it is exposed to the environment. Therefore, during the charging and storage of the battery, the environmental conditions should meet the requirements for battery usage. If the charging or battery storage environment does not meet the usage requirements, it may shorten the battery's lifespan. The specific regulations are as follows:

(1) Charging:

- Temperature: 0° C ~ 45 °C
- Humidity: 25% RH ~75% RH

(2) Storage:

- Temperature: -20°C~ 60 °C(Whitin 1 month), -20 °C~ 45 °C(Whitin 3 months), 20 °C±5 °C (Whitin 6 months).
- Humidity: 25% RH ~50% RH

#### △Caution

The battery should not be exposed to or immersed in any liquids, as this may damage the battery.

It is recommended to charge the battery to a level of 30% to 50% before storing it to maintain the battery's lifespan.



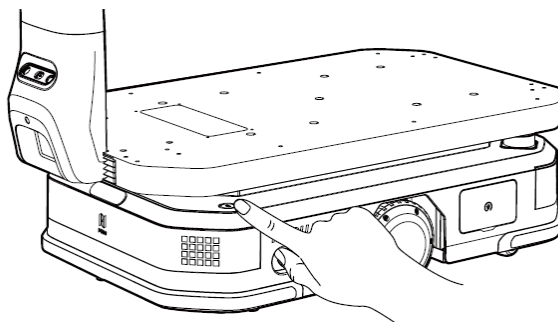
If the robot is not used for a long period (more than 15 days), it is recommended to remove the battery to avoid excessive discharge of the battery.

## 4. How to Use

### 4.1 Basic Operations

#### 4.1.1 Power On and Power Off

The power on and power off of the robot can be achieved by operating the power switch button. The power switch button is located on the base of the robot.



**Powering on:** Move the robot to the startup location. Press and hold the power switch until all chassis indicator lights turn blue, indicating that the robot has been successfully powered on.

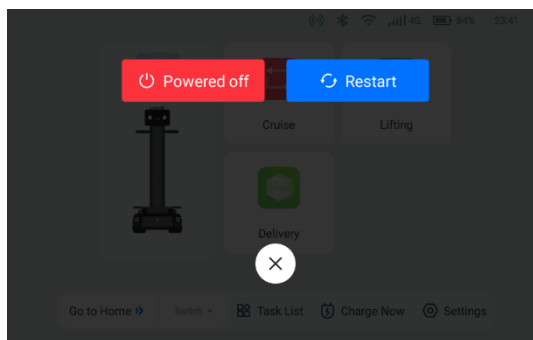
**Powered off:**

- Standard version: Press and hold the power switch for 3 seconds, and a shutdown prompt will pop up. Click "Power off".
- Underride version: Press and hold the power switch for 8 seconds.

All the indicator light of the robot turn off, indicating that the robot has been successfully powered off.



Power on — All indicator lights turn on

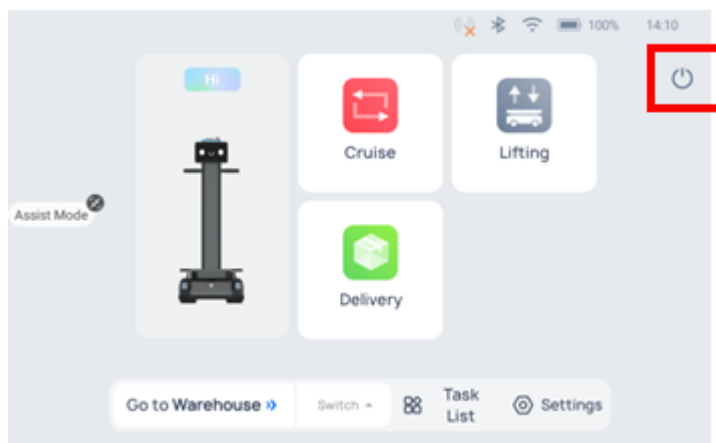


Power off — Shutdown confirmation pop-up

For the home control interface, "Powered off/Restart" serves as a quick access feature, allowing users to trigger power operations with a single click on the device's main screen. This eliminates the inconvenience of having to crouch down and long-press the physical power button.

Step 1 Click the  button.

Step 2 Select "Powered" or "Restart" to complete the operation



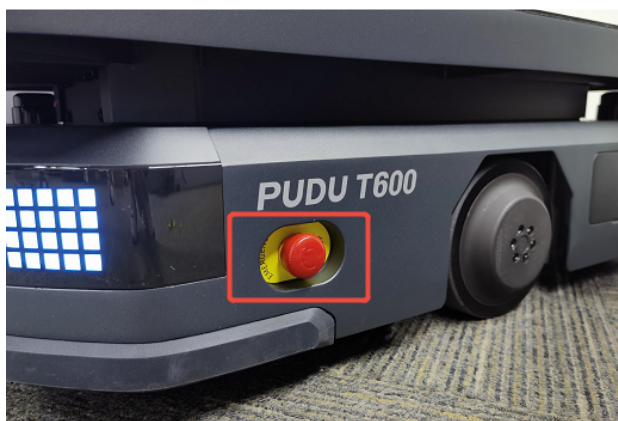
#### △Note

To prevent accidental shutdown or restart, an administrator password can be set under "Settings" - "Password & Security". Once set, clicking the  button will require password entry before proceeding with the "Powered off" or "Restart" action.

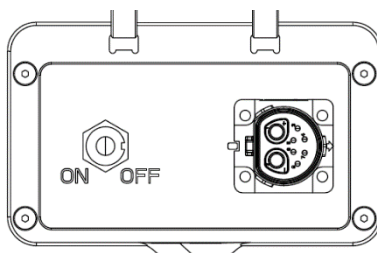
For the Underride Version robots, the visual interface of the robot can be viewed and operated via "Remote Control" in the cloud platform.

### 4.1.2 Emergency Stop Switch

There are emergency stop switches located on the top and on both sides of the base of the robot. In case of an emergency during operation, the emergency stop switch can be pressed to halt the robot's movement. To restore the robot's operation, rotate the emergency stop switch clockwise as indicated on the interface.



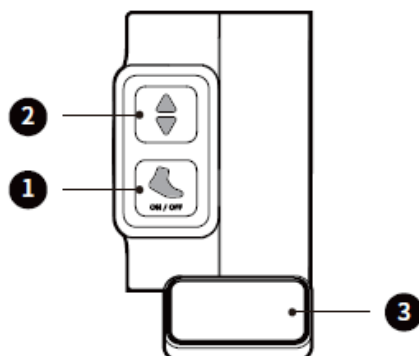
### 4.1.3 Brake Switch



The brake switch is only used to take effect after the robot has stopped. When the brake switch is "ON", the motor will automatically stop for safety during an emergency stop. If you

want to push the robot, you need to set the brake switch to "OFF".

#### 4.1.4 Booster



| No. | Name                 | Description                                                                                                    |
|-----|----------------------|----------------------------------------------------------------------------------------------------------------|
| 1   | Power assist switch  | :Turns the assist function on/off.                                                                             |
| 2   | Direction switch key | Switches the power assist direction.                                                                           |
| 3   | Throttle             | When pressed, it activates the power assist function. The harder it is pressed, the stronger the assist power. |

\* The booster is only equipped with the Standard version robot.

## 4.2 Operating Configuration Instructions

T600 is a series product that allows users to flexibly connect external structures and hardware. Before using the robot, it is necessary to configure the robot's operating parameters correctly by clicking on "Settings" - "Robot Functions" - "Run Setting" on the robot's homepage.

### 4.2.1 Robot Unloaded Parameters

Users can fix brackets or other structures on the T600 load surface according to their actual application needs. We define the state of the robot with the bracket fixed but without any load attached as the "Unloaded" of the robot.

### 4.2.2 Length and Width Dimensions Design

#### a) Structural Design

To ensure safe use, the following considerations should be taken into account when designing the installation of external fixed structures:

|                  | Description                                                                                                                                                                                                                                                                                                                                                                                                                            |
|------------------|----------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| Standard version | <ul style="list-style-type: none"> <li>After the installation of the external structure, the fixed bracket should not exceed 350mm (13.78 inches) on either side of the robot's chassis outline</li> <li>After the installation of the external structure, it should not extend beyond 400mm (15.74 inches) at the rear of the robot</li> <li>After the installation of the external structure, it should not extend beyond</li> </ul> |

|                   |                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                   |
|-------------------|-----------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
|                   | the front pillar of the robot.                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                    |
| Underride version | <ul style="list-style-type: none"> <li>After the installation of the external structure, the fixed structure should not exceed 350mm (13.78 inches) on either side of the robot's chassis outline</li> <li>After the installation of the external structure, it should not exceed beyond 400mm at the rear of the robot</li> <li>After the external structure is installed, do not exceed beyond 400mm the rear side of the robot chassis.</li> <li>The designed load-bearing center of the load space should coincide with the robot's center as closely as possible.</li> </ul> |

## b) Parameter Configuration

In the "Run Settings" section, the default values have been set for the robot's state without any structures installed. Considering the differences in structure and modification possibilities across various robot models, the page has been configured with different parameters for each model.

|                   |                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                  |
|-------------------|----------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
|                   | Description                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                      |
| Standard version  | <ul style="list-style-type: none"> <li>Rear Overhang (X): The distance the custom structure protrudes beyond the rear side of the robot chassis after installation. Input Range: 0–400   Default: 0   Unit: mm;</li> <li>Total Width (Y): The total width of the T600 robot combined with the custom structure after installation. Input Range: 500–1200   Default: 500   Unit: mm</li> </ul>                                                                                                                                                                                    |
| Underride version | <ul style="list-style-type: none"> <li>Front Overhang (W): The distance the custom structure protrudes beyond the front side of the robot chassis after installation. Input Range: 0–400   Default: 0   Unit: mm</li> <li>Rear Overhang (X): The distance the custom structure protrudes beyond the rear side of the robot chassis after installation. Input Range: 0–400   Default: 0   Unit: mm;</li> <li>Total Width (Y): The total width of the T600 robot combined with the custom structure after installation. Input Range: 500–1200   Default: 500   Unit: mm</li> </ul> |

After inputting the corresponding parameters, T600 will take into account the dimensions of the outline after fixing the structure to avoid collisions with surrounding obstacles.

During the parameter input process, the current robot's minimum pass width and minimum width for U-turn will be displayed in real-time.

### 4.2.2.2 Height Dimensions Design

#### a) Structural Design

For the external structure, the clear height is not recommended to exceed 1100mm. If the height is excessive, the following impacts may occur:

- The center of gravity of the load is raised, posing a risk during robot operation.

- It may obstruct the top-view camera of the standard T600 model, thereby affecting the robot's positioning during operation.

To ensure safe use, the following considerations should be taken into account when designing the installation of external fixed structures:

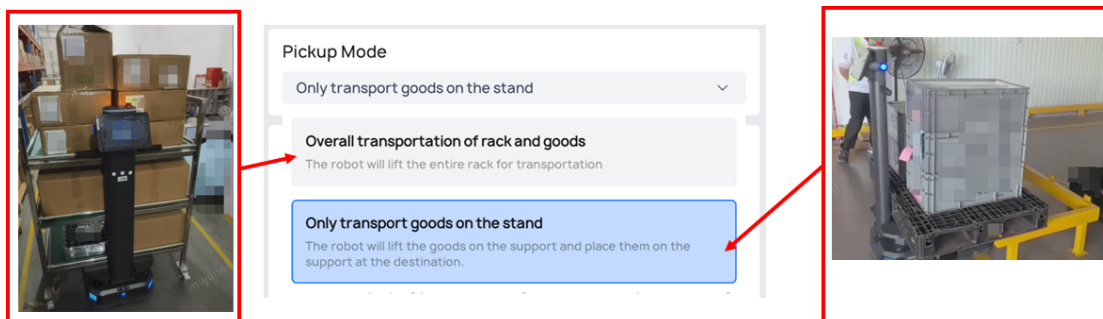


### 4.2.3 Parameters Related to the Lifting Function

The usage of the robot's lifting function can be categorized into two main types:

- (1) Overall transportation of rack and goods: Goods are placed on a movable rack, and when the robot performs the transport task, it takes the entire rack away.
- (2) Only transport goods on the stand: Goods are temporarily stored on a fixed stand, and when the robot performs the transport task, it only takes the goods on the fixed stand.

Based on the actual usage requirements on site, navigate to "Settings" - "Robot Functions" - "Run Settings" - "Lifting Settings," and in the "Picking Method," select the desired operational mode.



#### 4.2.3.1 Overall Transportation of Rack and Goods

The rack transported by the robot during lifting operations provides a larger carrying capacity than the robot's chassis. The T600 chassis can drive under the rack, lift it, and transport it.

Based on the rack's characteristics and the robot's recognition principles, racks are divided into two categories:

- (1) Racks with four legs in a rectangular arrangement: The LiDAR detects the four legs to determine the rack's position, enabling the robot to drive under it and perform lifting.
- (2) Other types of racks: This includes racks without legs or those with four legs that are not arranged in a rectangle.

##### a) Parameter Configuration

During configuration, the two types of racks must be configured separately. The specific

parameters are as follows:

### Lifting Status ?

Default

Rack Side Length for Vertical RobotA (800 - 1200)

900

Rack Side Length for Parallel RobotB (300 - 1000)

660

Rack Post LengthC (10 - 50)

30

Rack Post WidthD (10 - 50)

30

Clearance LengthE (600 - 1200)

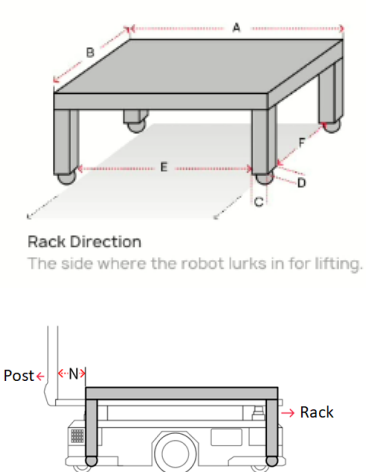
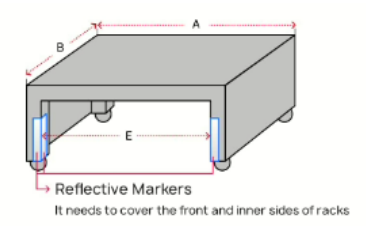
760

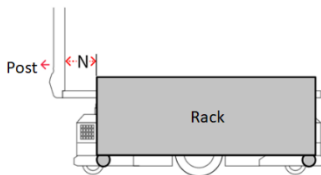
Clearance WidthF (300 - 1000)

550

Minimum Passage Width for Passthrough During Lifting: 1080

Minimum Passage Width for Turnaround During Lifting: 1450

|                                                                  | Description                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                          | Illustration                                                                                                                                                                   |
|------------------------------------------------------------------|--------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|--------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| Four-legged rack                                                 | <p>(1) Basic parameter (Rack dimension)</p> <ul style="list-style-type: none"> <li>Rack Length A: 600mm~1200mm</li> <li>Rack Length B: 300mm~1000mm</li> <li>Rack Post Length &amp; Width (C&amp;D): 10mm~50mm</li> <li>Clearance Length E : 600mm~1200mm</li> <li>Clearance Width F: 300mm~1000mm</li> </ul> <p>(2) Advanced Parameter Settings</p> <ul style="list-style-type: none"> <li>Distance between robot post and rack N: 0~250mm. The distance between the uprights and the rack legs in the front-to-back direction of the robot can be adjusted when the robot is lifting.</li> <li>Exit rack correction range: After placing the goods, the robot will move forward briefly. This distance can be adjusted.</li> </ul> |  <p><b>Rack Direction</b><br/>The side where the robot lurks in for lifting.</p>            |
| Other type of racks<br>(There are no four legs in a rectangular) | <p>(1) Basic parameter (Rack dimension)</p> <ul style="list-style-type: none"> <li>Rack Length A: 600mm~1200mm</li> <li>Rack Length B: 300mm~1000mm</li> <li>Reflective Markers Spacing E: 600mm~1200mm</li> </ul> <p>(2) Advanced Parameter Settings</p>                                                                                                                                                                                                                                                                                                                                                                                                                                                                            |  <p><b>Reflective Markers</b><br/>It needs to cover the front and inner sides of racks</p> |

|               |                                                                                                                                                                                               |                                                                                    |
|---------------|-----------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|------------------------------------------------------------------------------------|
| distribution) | Distance between robot post and rack N:<br>0~250mm. The distance between the uprights and the rack legs in the front-to-back direction of the robot can be adjusted when the robot is lifting |  |
|---------------|-----------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|------------------------------------------------------------------------------------|

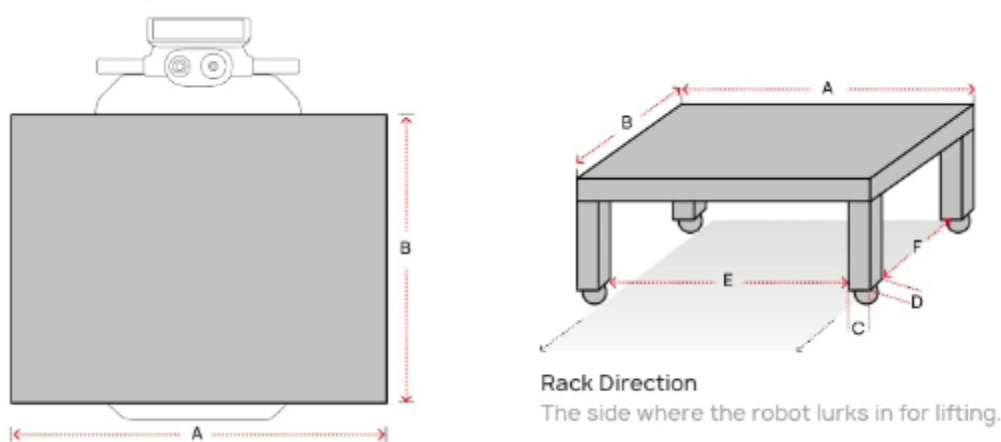
Note: If the site uses racks of multiple sizes, multiple rack dimensions can be pre-registered in the robot's system. When identifying a rack, the robot will compare the target rack against all the configured parameters for both four-legged racks and other racks in the settings. Upon successful identification, it will trigger the lifting mechanism to raise and, based on the input rack dimensions, perform an algorithmic contour expansion.

#### ⚠Caution

- To avoid operational risks caused by misidentification, it is recommended that the "Dimension C+E" of any two racks differs by more than 100mm, or their "Dimension D+F" differs by more than 100mm.。
- A maximum of 20 rack parameter sets can be configured.

### b) Structural Design

The rack size parameters provided by Pudu are as follows:

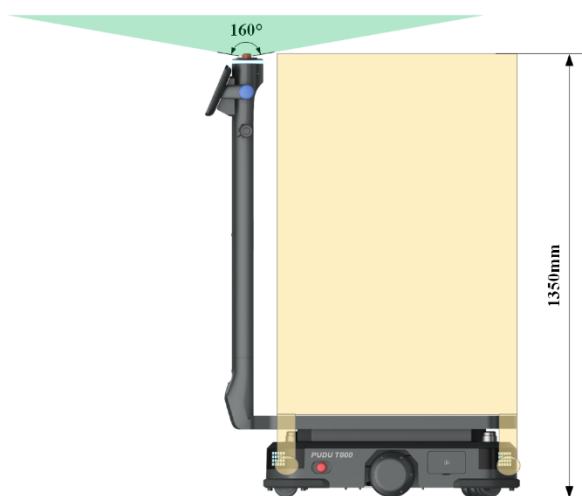


The rack dimensions provided by PUDU are as follows:

- Overall dimensions (length \* width \* height): 900mm\*660mm\*308mm / 35.43inch\*25.98inch\*12.13inch
- Load surface dimensions (length \* width): 820mm\*610mm / 32.28inch\*2.40inch
- Rack post dimensions (length \* width): 30mm\*30mm / 1.18inch\*1.18inch
- Height from the ground to the bottom of the rack load surface: 275mm / 10.83inch

If you have specific requirements for the size of the rack, the use of four-legged rack is recommended. Please follow the guidelines below to create the rack and configure the parameters accordingly.

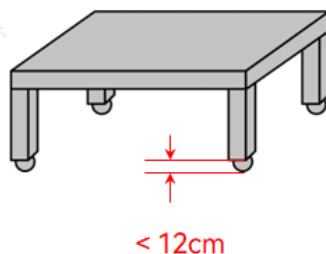
- Rack length (dimension A): 600mm ~ 1200mm (recommended 700mm ~ 1000mm)
- Rack width (dimension B): 300mm ~ 1000mm (recommended 500mm ~ 900mm)
- Rack bottom height (dimension G): 270mm ~ 280mm
- Rack posts width (dimension C, dimension D): 10mm ~ 50mm (recommended 30mm ~ 50mm)
- Clearance length (dimension E): 600mm ~ 1200mm (recommended 600mm ~ 940mm)
- Clearance width (dimension F): 300mm ~ 1000mm (recommended 400mm ~ 840mm)
- Rack height: no more than 1350mm (to prevent the robot's top view camera be obstructed when lifting status, which could affect the stability of the robot's positioning during operation).



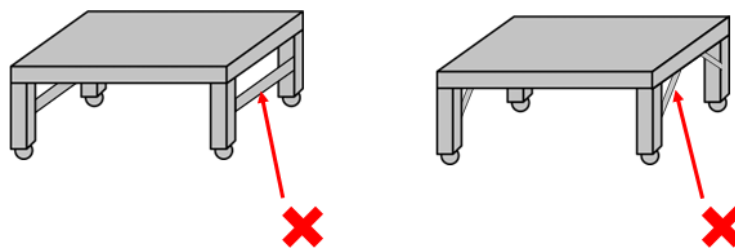
#### ● Others

Combined with the structure and operation principle of T600, there are also the following requirements:

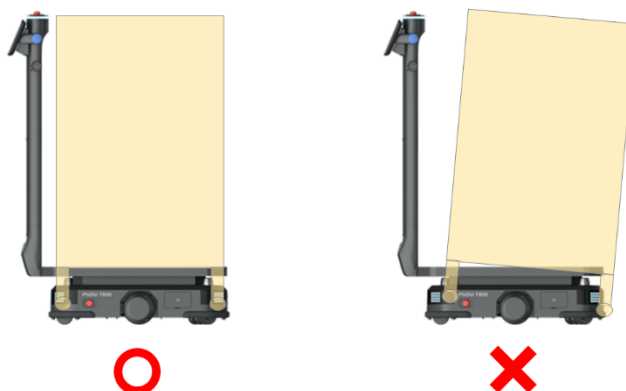
- (1) Ensure that there are only rack legs within the horizontal range of 12cm~21cm (4.72inches~8.27inches) above the ground. Specifically:
  - a. The universal wheels of the rack and its fixed surface need to be lower than 12cm (4.72inches).



- b. There should be no supporting triangle structure or reinforcement structure within the range of 12~21cm (4.72inches~8.27inches), such as:



(2) The bottom of the rack needs to be reasonably designed so that the rack can be placed firmly on the load surface of T600.



#### 4.2.3.2 Only Transport Goods on the Stand

In this application method, the goods themselves do not have support legs. During operation at the customer site, the goods are placed on temporary storage stands to facilitate lifting and transportation by the robot.

Based on the rack's characteristics and the robot's recognition principles, racks are divided into two categories:

- (1) Racks with four legs in a rectangular arrangement: The LiDAR detects the four legs to determine the rack's position, enabling the robot to drive under it and perform lifting.
- (2) Other types of racks: This includes racks without legs or those with four legs that are not arranged in a rectangle.

##### a) Parameter Configuration

During configuration, the two types of stands must be configured separately. The specific parameters are as follows:

|                      | Description                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                            | Illustration |
|----------------------|------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|--------------|
| Four-legged stand    | <p>(1) Basic parameter</p> <ul style="list-style-type: none"> <li>Good Length A: 600mm~1200mm</li> <li>Good Length B: 300mm~1000mm</li> <li>Stand Post Length &amp; Width (C&amp;D): 10mm~50mm</li> <li>Clearance Length E: 600mm~1200mm</li> <li>Clearance Width F: 300mm~1000mm</li> </ul> <p>(2) Advanced Parameter Settings</p> <ul style="list-style-type: none"> <li>Distance between robot post and stand N: 0~250mm. The distance between the uprights and the stand legs in the front-to-back direction of the robot can be adjusted when the robot is lifting.</li> <li>Exit stand correction range: After placing the goods, the robot will move forward briefly. This distance can be adjusted.</li> </ul> |              |
| Other type of stands | <p>(1) Basic parameter</p> <ul style="list-style-type: none"> <li>Good Length A: 600mm~1200mm</li> <li>Good Length B: 300mm~1000mm</li> <li>Reflective Markers Spacing E: 600mm~1200mm</li> </ul> <p>(2) Advanced Parameter Settings</p> <p>Distance between robot post and stand N: 0~250mm. The distance between the uprights and the stand legs in the front-to-back direction of the robot can be adjusted when the robot is lifting.</p>                                                                                                                                                                                                                                                                          |              |

Note: If the site uses stands of multiple sizes, multiple stand dimensions can be pre-registered in the robot's system. When identifying a stand, the robot will compare the target stand against all the configured parameters for both four-legged stands and other stands in the settings. Upon successful identification, it will trigger the lifting mechanism to raise and, based on the input stand dimensions, perform an algorithmic contour expansion.

#### ⚠Caution

- To avoid operational risks caused by misidentification, it is recommended that the "Dimension C+E" of any two stands differs by more than 100mm, or their "Dimension D+F" differs by more than

100mm.。

- A maximum of 20 rack parameter sets can be configured.

## b) Structural Design

If you require custom lifting stands, the use of four-legged stands is also recommended. The robot can identify four-legged stands more accurately, ensuring safer operation. Please fabricate the stands according to the following requirements and configure the parameters correctly.

- Stand Top Height (Dimension G): 270mm~280mm
- Stand Leg Width (Dimension C, Dimension D): 10mm~50mm (Recommended: 30mm ~ 50mm)
- Distance between stand legs on the Robot Approach Side (Dimension E): 600mm~1200mm (Recommended: 600mm ~ 940mm)
- Distance between stand legs on the Robot Parallel Side (Dimension F): 300mm~1000mm (Recommended: 400mm ~ 840mm)

## 4.3 Mode Introduction

To accommodate different operational scenarios, the robot offers multiple mode options:

| Mode          | Description                                                                                                                                                                                                                                                                                         |
|---------------|-----------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| Delivery mode | Users can place materials for multiple destinations on the robot and use the screen to send tasks for materials delivery. The robot can plan the best path by itself and deliver the items to all destinations. After the delivery is completed, it will automatically return to the standby point. |
| Cruise mode   | User can set the path, and the robot will run along the pre-set path in a cycle. In addition, the robot can stop at a stop point on the cruise path, to make it easier for the user to pick up and place materials while the robot is running.                                                      |
| Lifting mode  | Users can set lifting points and lifting down points. The robot will automatically go to the lifting point to identify and lift the materials, and then automatically unload the materials after transporting them to the destination.                                                              |
| Roller mode * | Users can set task points and define robotic actions, enabling the robot to interface with conveyors at designated locations and automatically perform loading and unloading tasks, thereby achieving fully automated material handling.                                                            |

\* The roller mode requires the installation of PUDU Conveyor accessory for support.

### 4.3.1 Create Tasks

The T600 series robot supports a variety of task creation and distribution methods, as detailed in the table below.

| Method | Discription |
|--------|-------------|
|--------|-------------|

|               |                                                                            |
|---------------|----------------------------------------------------------------------------|
| Robot screen* | Select features from the homepage of the robots' screens.                  |
| Pager         | Send instructions to the robot via pudu pager paired with the gateway.     |
| Internet      | Send instructions through pudulink APP, business management platform, etc. |

\*Not applicable on T600 override.

#### 4.3.1.1 Create Tasks via Robot Screens

Once the robot is turned on, select the function on the homepage of the screen, as described in 4.2.2-4.3.5, to create a task.

#### 4.3.1.2 Create Tasks via Pudulink Pagers

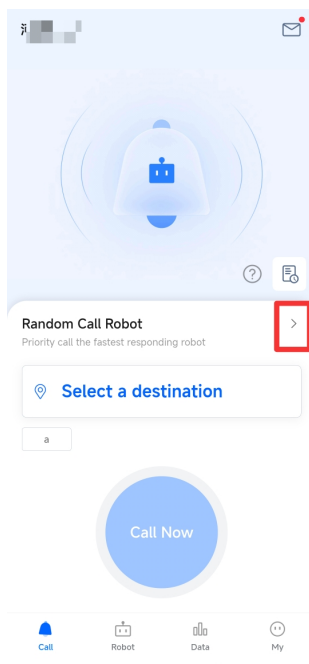
Please reach pudu technical support for more details on how to deploy pagers and gateway.

#### 4.3.1.3 Create Tasks through Internet

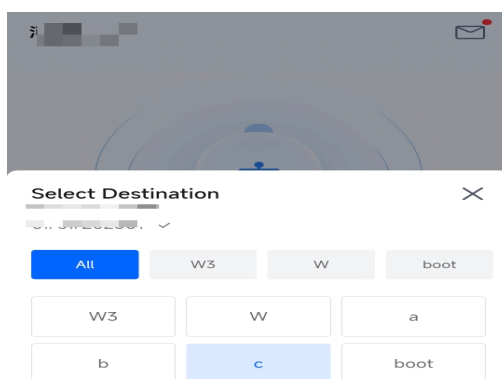
After the machine is connected to each other, it can send tasks through the pudulink APP, APIs and business management platform.

(1) Use Pudulink APP

Step 1 Login pudulink APP, select the machine you want to verify under the store, or select random call robot.

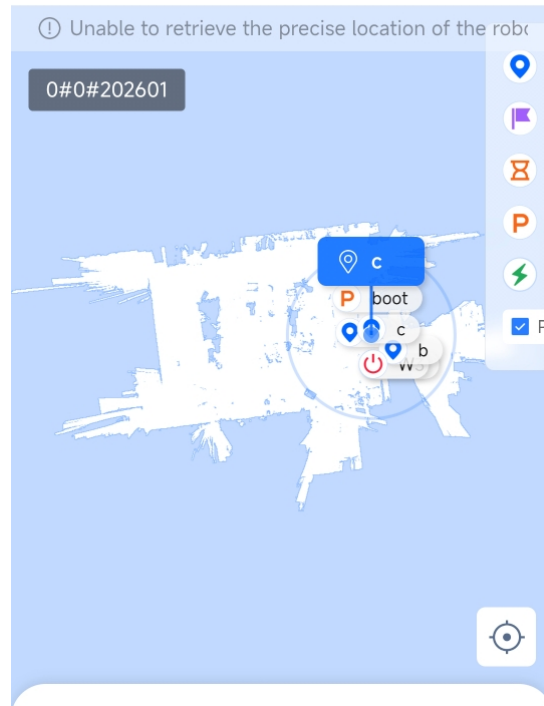


Step 2 After selecting picking point, assign the task to the robot.



Step 3 User can monitor the robot on the app

## Call the robot



Robot on the way...

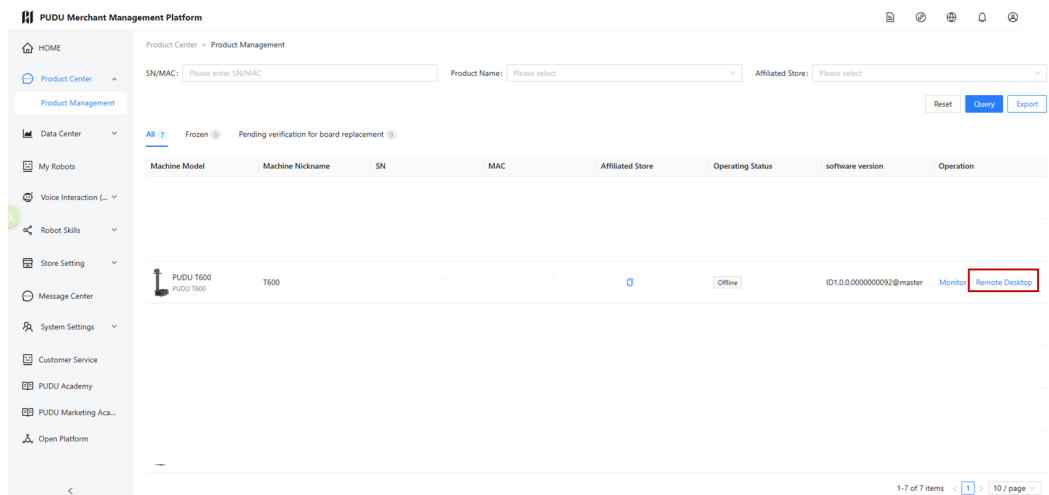


Waiting Time: 00:06



## (2) Remote access through the merchant management platform

Log in to the merchant management platform, access the robot screen from a remote desktop, and issue tasks through the actions described in 4.2.2-4.3.5.



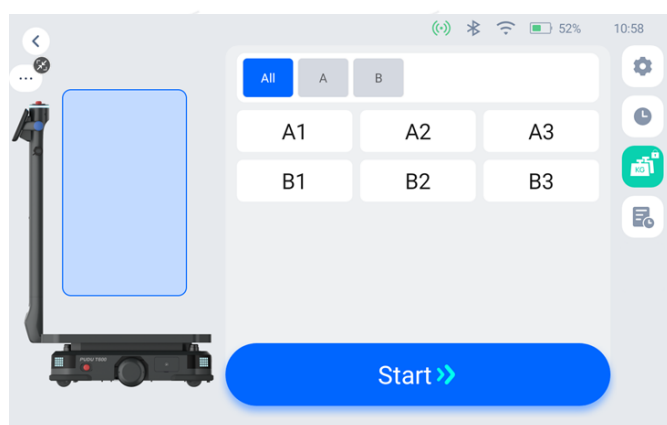
### 4.3.2 Delivery Mode

In Delivery Mode, an item is delivered to a specified destination, with automatic return to the docking location after completing delivery to the final destination.

#### 4.3.2.1 The Main Processes of Delivery Mode

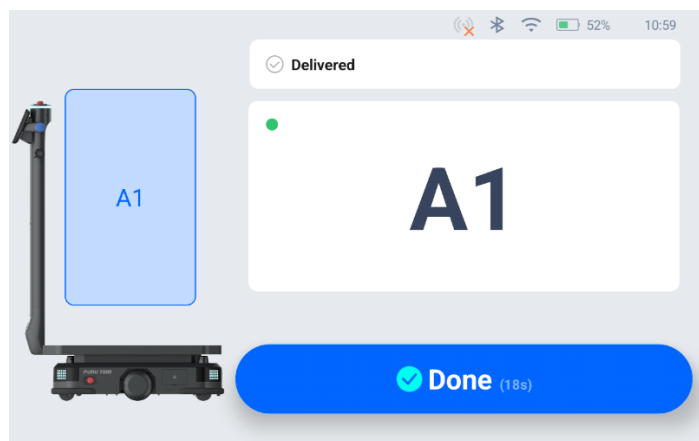
**Step 1** On the robot's home page, select “Delivery” to access the main interface for delivery mode. And place the items on the corresponding load area.

**Step 2** On the left side of the interface, click on the load area where the item is placed and select the destination on the right side.



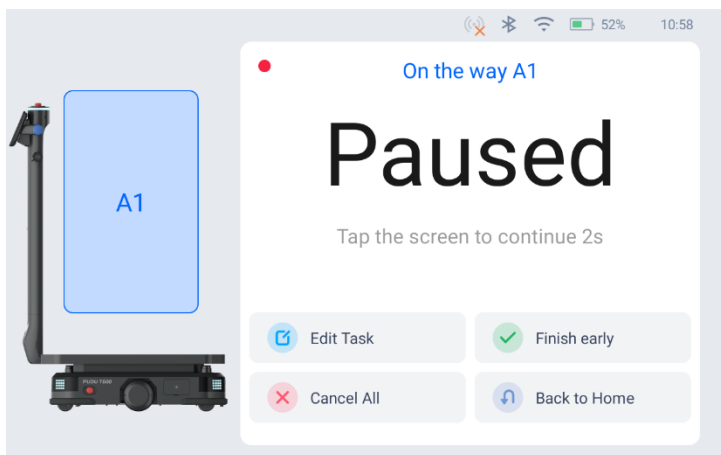
**Step 3** Once you have finished entering the destination, tap “Start”. The robot will proceed to the corresponding destination.

**Step 4** Once it reaches its destination, the robot will give a voice prompt. The operator will remove the item in accordance with the on-screen and voice prompts.



**Step 5** Once the operator removes the item, tap “Done”, and the robot will then begin executing its next task. If the robot has completed all tasks, it will return to the docking location.

During the delivery process, if it is necessary to edit a task, remove a meal in advance, cancel all tasks, or return, you can tap on the robot’s screen to pause the robot before proceeding with the operation. If there are no operations during the countdown period, the robot will continue running



| Button        | Description                                                              |
|---------------|--------------------------------------------------------------------------|
| Modify task   | Tap to modify the destination.                                           |
| Pick up early | Tap to Complete in advance and move on to the next task.                 |
| Cancel all    | Tap to cancel all delivery tasks and not return to the docking location. |
| Return        | Tap to return to the docking location.                                   |

#### 4.3.2.2 Description of Delivery Mode Homepage

The delivery mode homepage features the following buttons:

| Illustration | Settings               | Descriptions                                                         |
|--------------|------------------------|----------------------------------------------------------------------|
|              | Previous Task          | You can view the previous task.                                      |
|              | Steady Mode            | When enabled, the robot can travel at a low speed and move smoothly. |
|              | History of Tasks       | You can view the previous task executed in the current mode.         |
|              | Delivery Mode Settings | You can make configurations for the delivery mode.                   |

Detail explanation:

##### (1) Previous Task



Click the " " button on the delivery mode homepage to view the robot's last delivery task.

##### (2) Steady Mode

You can choose whether the robot uses the smooth mode during the delivery process. In steady mode, the robot will travel at a lower speed. It will start and brake in a relatively gentle manner. It is suitable for delivering items that require the robot to run smoothly. Usage is as follows:

- Click the " " icon on the right side of the delivery interface, and the icon changes to " "



", which turns on the smooth mode, which is valid for one time. Click again to turn off the smooth mode;

- Press and hold the delivery icon for 2s, and the icon changes to "", which turns on the smooth mode continuously. Click again to turn off the smooth mode.

### (3) History of Tasks



Click the "  " button on the delivery mode homepage to view the robot's recent historical delivery tasks.

### (4) Delivery Mode settings

There is a " " button on the right side of the delivery mode interface. Click it to set the delivery mode. The settings are as follows:

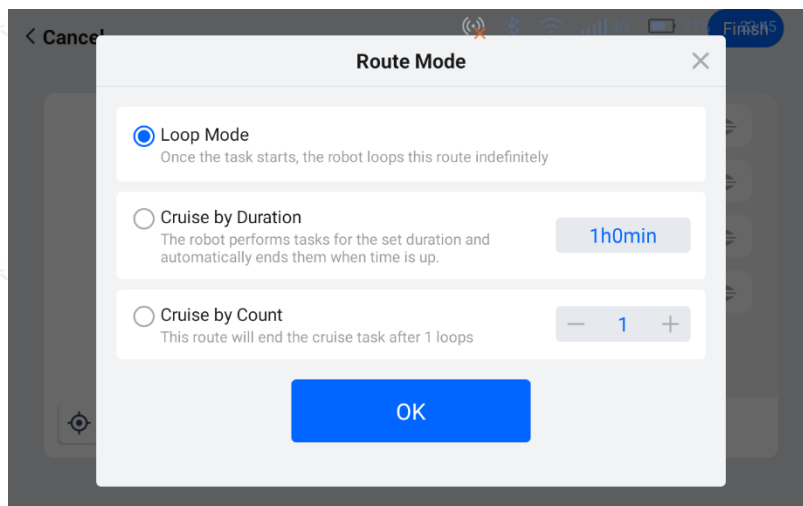
| Settings                         | Description                                                                                                                                                                                                                                                                                                                                                                                                             |
|----------------------------------|-------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| Destination Priority             | <p>You can set the way the robot goes to the target point in the case of multiple tasks:</p> <ul style="list-style-type: none"> <li>● Distance Priority: The robot intelligently finds the shortest route and arrives at all the selected target points in sequence according to the distance;</li> <li>● Sequence Priority: The robot arrives in sequence according to the order of the input destinations.</li> </ul> |
| Auto-complete time after arrival | The robot will count down automatically after arriving at the destination. If no one is operating the robot, the robot will leave automatically after the countdown ends.                                                                                                                                                                                                                                               |
| Delivery Complete, Returning     | You can set the location where the robot returns after the delivery is completed.                                                                                                                                                                                                                                                                                                                                       |
| Custom Function Button           | <p>Set the robot's action after the shortcut button is pressed:</p> <ul style="list-style-type: none"> <li>● No action: No action after pressing the shortcut button;</li> <li>● Complete the current task: When the robot is on the delivery arrival page, press the shortcut button and the robot will automatically complete the current task.</li> </ul>                                                            |
| Play during tasks                | When enable, you can select the synthesized voice or music file to play during the delivery task.                                                                                                                                                                                                                                                                                                                       |
| Play upon arrival                | When enable, you can select the synthesized voice or music file to play when the delivery task arrives at the destination                                                                                                                                                                                                                                                                                               |
| Single Layer Multi-point         | After turning on this function, a single load area can correspond to multiple locations for delivery.                                                                                                                                                                                                                                                                                                                   |
| Delivery Speed                   | The robot's scheduled driving speed to the destination can be configured, with a setting range of 0.2m/s~1.2m/s.                                                                                                                                                                                                                                                                                                        |

### 4.3.3 Cruise Mode

Cruise mode means cruising in a specific environment and running in a loop. Some voice and music can be played during the cruise.

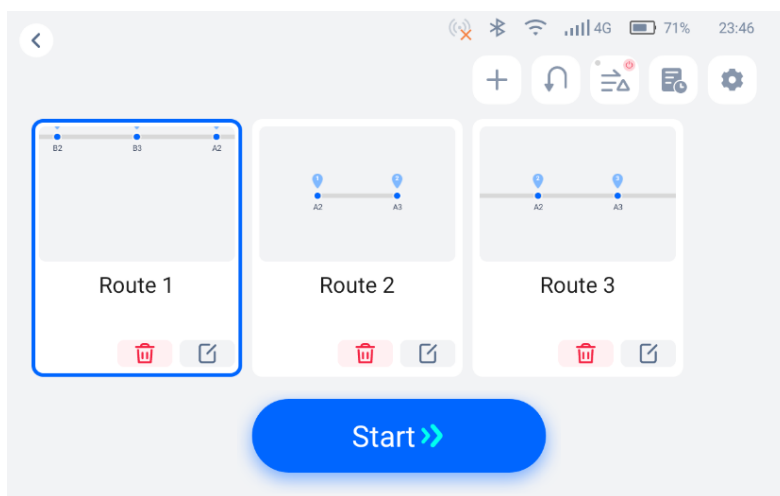
#### 4.3.3.1 The Main Processes of Cruise Mode

Step 1 Select "Cruise" on the homepage. Enter the cruise mode interface and click "+" to add a cruise path according to the instructions. There are three types of cruise paths that can be added:



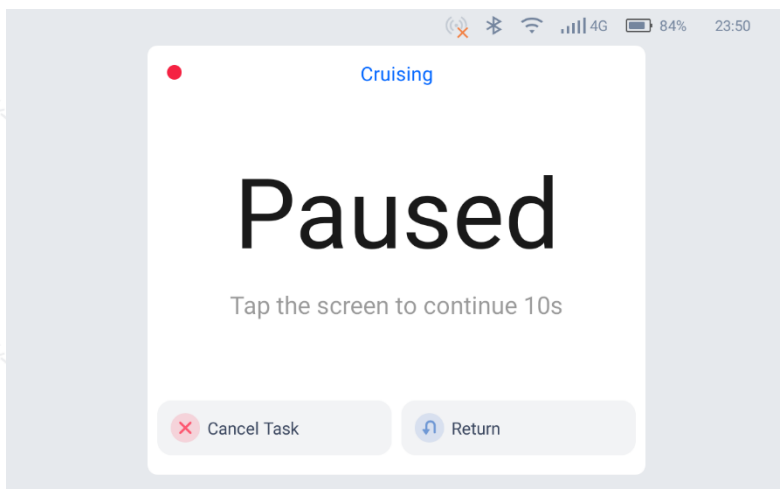
- **Loop Mode:** After the cruise task starts, it will continue to cruise along the set cruise path;
- **Cruise by Duration:** Cruise according to the set time, and automatically end the task after the cruise ends;
- **Cruise by Count:** After the robot cruises a specified number of laps, it will automatically end the cruise task.

Step 2 After setting the cruise route, select the cruise route you want to use and click "Start". The robot starts to run in a cycle along the cruise route.

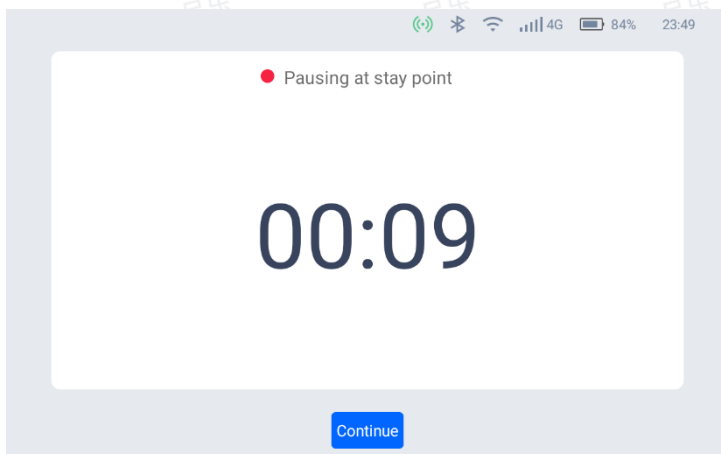


Step 3 During the robot's cruising, the user can click on the robot screen to pause. After the pause countdown ends, the robot will continue to perform the cruising task.

- If you click "Cancel Task" during the pause process, you can end the cruising task.



- If a stop point is set on the cruising path, the robot will drive to the stay point and stop. During the stop process, you can click "Continue" and the machine will go directly to the next point.



#### 4.3.3.2 Description of Cruise Mode Homepage

The cruise mode homepage features the following buttons:

| Illustration                                                                        | Settings             | Descriptions                                                                                |
|-------------------------------------------------------------------------------------|----------------------|---------------------------------------------------------------------------------------------|
|  | Add Cruise Path      | Clicking on this option allows you to add a new cruise path for the robot.                  |
|  | Return               | Clicking on this option will initiate the robot's automatic return to the docking location. |
|  | Steady Mode          | When enabled, the robot can travel at a low speed and move smoothly.                        |
|  | History of Tasks     | You can view the previous task executed in the current mode.                                |
|  | Cruise Mode Settings | You can make configurations for the cruise mode.                                            |

Detail explanation:

### (1) Add Cruise Path

Just follow the steps in the previous section.

### (2) Return

After clicking "", the robot will automatically return to the standby point.

### (3) Steady Mode

You can choose whether the robot uses the smooth mode during the delivery process. In steady mode, the robot will travel at a lower speed. It will start and brake in a relatively gentle manner. It is suitable for delivering items that require the robot to run smoothly. Usage is as follows:

Click the "" icon on the right side of the delivery interface, and the icon changes to "

", which turns on the smooth mode, which is valid for one time. Click again to turn off the smooth mode;

Press and hold the delivery icon for 2s, and the icon changes to "", which turns on the smooth mode continuously. Click again to turn off the smooth mode.

### (4) History of Tasks

Click the "" button on the cruise mode homepage to view the robot's recent historical cruise tasks.

### (5) Cruise Mode settings

There is a "" button on the right side of the cruise mode interface. Click it to set the cruise mode. The settings are as follows:

| Settings                               | Description                                                                                                                                                                                                                                                                                                                |
|----------------------------------------|----------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| On arriving at stop point              | Set the action when the robot reaches the stop point. You can choose:<br>Stay put: The robot stays at the stop point until the user clicks;<br>Keep moving: The robot does not stop at the stop point;<br>Stay Time: When the robot arrives at the stop point, it stays for a specified time and then continues to cruise. |
| Cruise complete, returning to position | You can set the location where the robot returns after completing the cruise task.                                                                                                                                                                                                                                         |
| Custom Function Button                 | Set the robot's action after the shortcut button is pressed:<br>No action: No action after pressing the shortcut button;<br>Complete the current task: When the robot is on the stop point arrival page, press the shortcut button and the robot will automatically continue cruising.                                     |
| Play during tasks                      | When enable, you can select the synthesized voice or music file to play during                                                                                                                                                                                                                                             |

|                 |                                                                                                                         |
|-----------------|-------------------------------------------------------------------------------------------------------------------------|
|                 | the cruise task.                                                                                                        |
| Play on arrival | When enable, you can select the synthesized voice or music file to play when the cruise task arrives at the stop point. |
| Cruise Speed    | The robot's scheduled driving speed in cruising can be configured, with a setting range of 0.2m/s~1.2m/s.               |

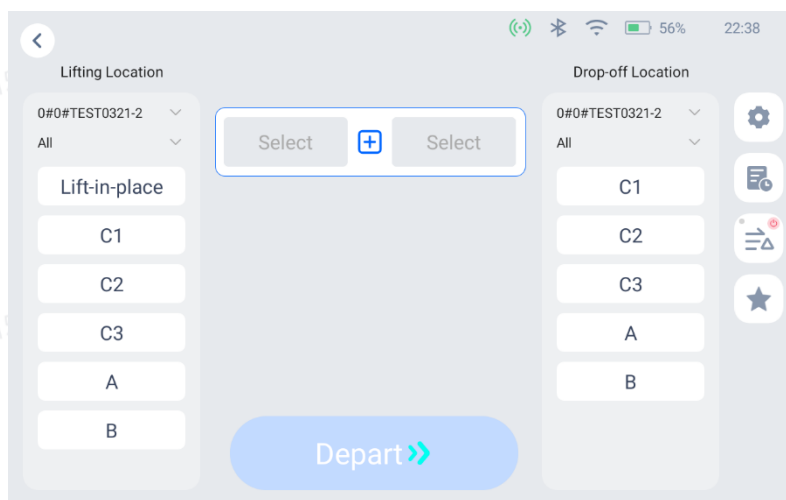
### 4.3.4 Lifting Mode

Users can set the lifting point and drop-off point. The robot will automatically go to the lifting point to identify and lift the goods, and then automatically unload the goods after transporting them to the destination. After completing all the set tasks, the robot will return to the docking location.

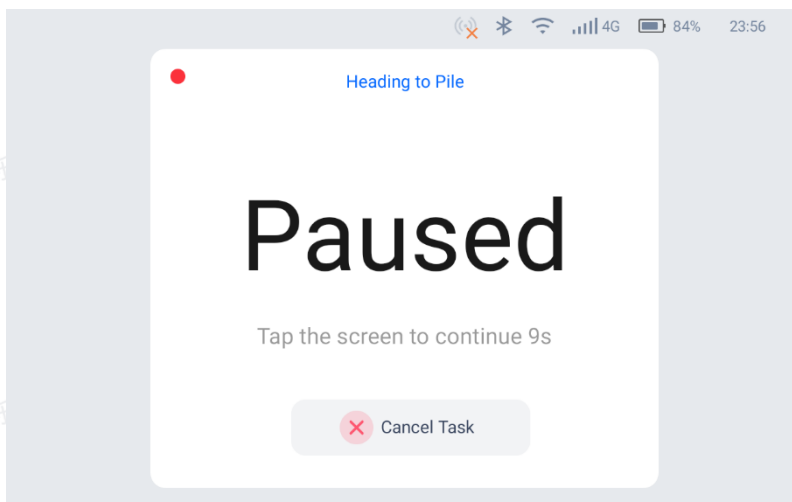
#### 4.3.4.1 The Main Processes of Lifting Mode

Step 1 Select "Lifting" on the homepage. Enter the lifting mode interface. Choose the desired lifting point from the list on the left and the drop-off point from the list on the right. After selecting the points, click "Depart" to initiate the task.

\*However, if the robot has already been pushed to the rack to be transported and you want the robot to lift the rack in place, please select "In-situ Lifting" in the lifting point list.

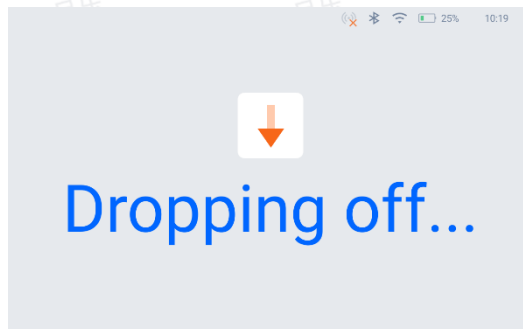
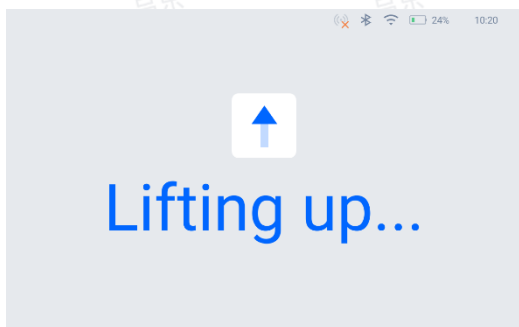


Step 2 During the lifting task, the user can click on the robot screen to pause. After the pause countdown ends, the robot will continue to perform the lifting task. If you click "Cancel Task" during the pause process, you can end the lifting task.

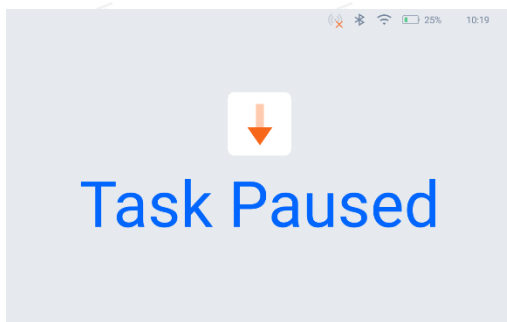


### ⚠Caution

To ensure the precise operation of the lifting mechanism, the robot cannot be paused when lifting up or drop-off goods. If you need to stop the lifting mechanism, please press the emergency stop button.



To ensure safety, during the lifting and lowering process, if an object approaches the front end of the robot, the lifting reset action will pause. Once the object is removed, the lifting mechanism will continue to execute the reset action.



#### 4.3.4.2 Description of Lifting Mode Homepage

The lifting mode homepage features the following buttons:

| Illustration | Settings         | Descriptions                                                                                                                            |
|--------------|------------------|-----------------------------------------------------------------------------------------------------------------------------------------|
|              | History of Tasks | You can view the previous task executed in the current mode.                                                                            |
|              | Steady Mode      | When enabled, the robot can operate with a stable control strategy during lifting transport, optimizing the stability of the robot when |

|                                                                                   |                       |                                                                                                                                           |
|-----------------------------------------------------------------------------------|-----------------------|-------------------------------------------------------------------------------------------------------------------------------------------|
|                                                                                   |                       | transporting large-sized and heavy-load goods.                                                                                            |
|  | Lifting Mode Settings | You can make configurations for the lifting mode.                                                                                         |
|  | Favorite Common Tasks | For saved tasks, you can view, apply, or edit them in the Saved Tasks list.                                                               |
|  | Apply a Saved Task    | To use a saved task, click "Apply" and the task details will be auto-populated in the interface. Then click "Depart" to execute the task. |

Detail explanation:

#### (1) History of Tasks

Click the " " button on the cruise mode homepage to view the robot's recent historical cruise tasks.

#### (2) Steady mode

When enabled, the robot can operate with a stable control strategy during lifting transport, optimizing the stability of the robot when transporting large-sized and heavy-load goods

Click the " " icon on the right side of the delivery interface, and the icon changes to " ", which turns on the smooth mode, which is valid for one time. Click again to turn off the smooth mode;

Press and hold the delivery icon for 2s, and the icon changes to " ", which turns on the smooth mode continuously. Click again to turn off the smooth mode.

#### (3) Lifting Mode settings

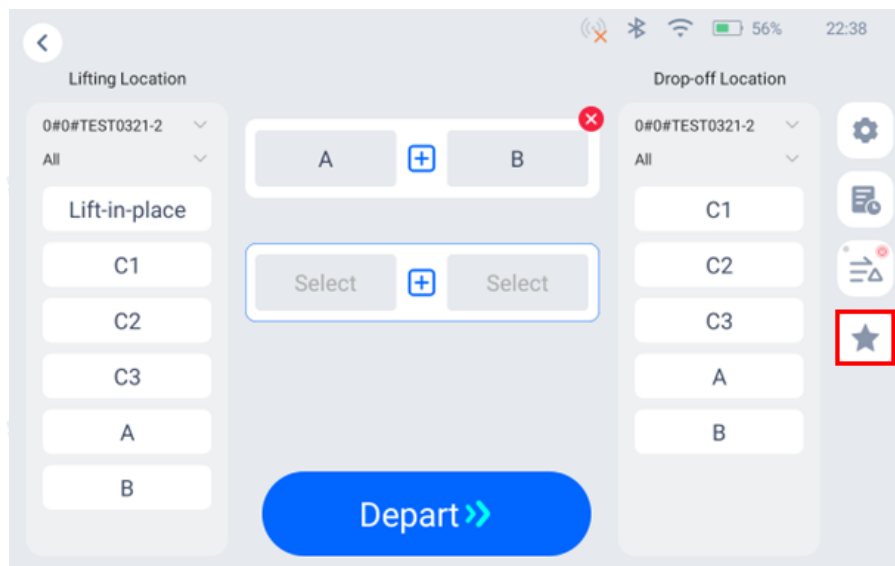
There is a " " button on the right side of the cruise mode interface. Click it to set the cruise mode. The settings are as follows:

| Settings                                | Description                                                                                                              |
|-----------------------------------------|--------------------------------------------------------------------------------------------------------------------------|
| Play during tasks                       | When enable, you can select the synthesized voice or music file to play during the lifting task.                         |
| Play upon arrival                       | When enable, you can select the synthesized voice or music file to play when the lifting task arrives at the destination |
| Lifting complete, returning to position | After the robot completes the lifting task, it will return to the designated location.                                   |
| Speed                                   | The robot's scheduled driving speed in cruising can be configured, with a setting range of 0.2m/s~1.2m/s.                |

#### (4) Task Favorite Function

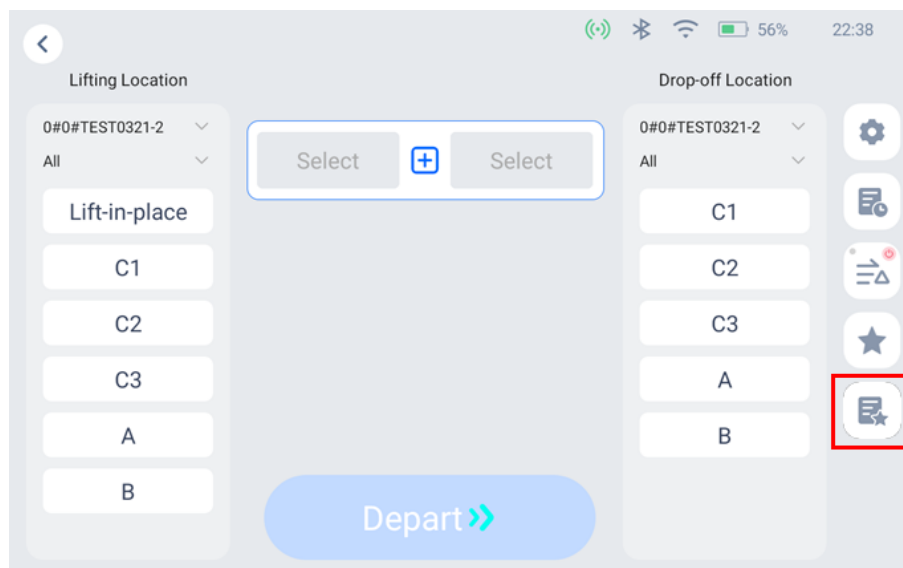
On the home page of the lifting mode, enter a frequently used task and click the "★" icon on the right side of the interface.

Frequently used tasks can be favorited and saved. Saved tasks can be viewed, applied, and edited in the saved task list.



#### (5) Apply Saved Tasks

Saved tasks can be viewed, edited, and applied in the saved task list.



Click the "★" icon on the right side of the interface to call up saved tasks. Two operations, Edit and Apply, are available for the tasks.

When Edit is selected, the favorited task can be modified.

For the task to be used, click Apply; the task information will be automatically imported into the interface. Click "Depart" to execute the task.

Task1

Lifting Location

A

Stationary Point

C1 C2 C3

Drop-off Location

B

Delete

Edit

Apply

#### 4.3.4.3 Description of Arrival Method

According to on-site requirements, the robot can be configured for lifting tasks, where it can either adjust its direction and back up to the stop point and drop-off point, or pivot in place after reaching the target point. This flexibility allows the robot's behavior to meet the diverse needs of different customers on-site.

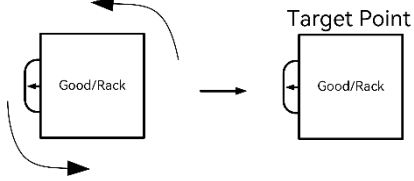
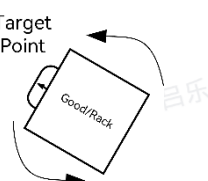
Arrival Method

☒
**Moving backward**

The robot will adjust its posture before reaching the target point and reverse to arrive. Suitable for situations where the target point is near a wall or in a narrow space.

☐
**Direct Arrival**

The robot will directly reach the target point and rotate in place upon arrival. Suitable for scenarios where the target location is open and free of obstacles.

| Arrival Method | Moving backward                                                                                                                                                   | Direct Arrival                                                                                                                                                                           |
|----------------|-------------------------------------------------------------------------------------------------------------------------------------------------------------------|------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| Description    | <p>Pursuing docking efficiency with ample space for the docking position.</p>  | <p>The robot directly reaches the target point location and then adjusts its docking direction.</p>  |
| Instructions   | The target point is against a wall or                                                                                                                             | Pursuing docking efficiency with                                                                                                                                                         |

|  |                                                                                                 |                                       |
|--|-------------------------------------------------------------------------------------------------|---------------------------------------|
|  | in a narrow space that is insufficient for the robot to pivot in place while carrying the load. | ample space for the docking position. |
|--|-------------------------------------------------------------------------------------------------|---------------------------------------|

### 4.3.5 Other Application

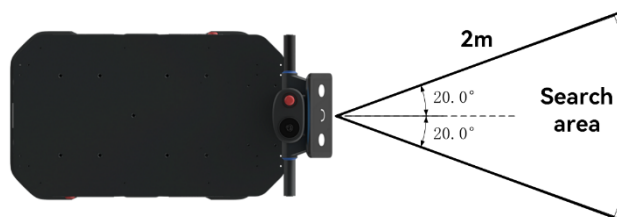
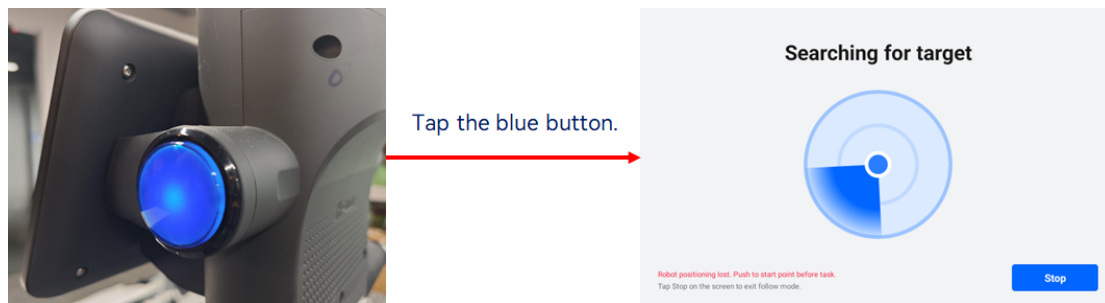
To facilitate a more flexible application of the PUDU T600, the robot is equipped with additional modes.

#### 4.3.5.1 Follow mode

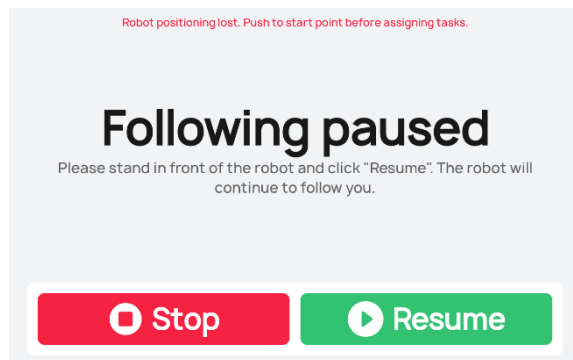
In follow mode, the T600 can use its sensors to follow a designated target object, performing semi-automated assistance for material handling. The specific usage method is as follows:

**Step 1** On the robot's homepage or the mode homepage, tap the blue buttons located on both sides of the T600 screen to enter the target searching state.

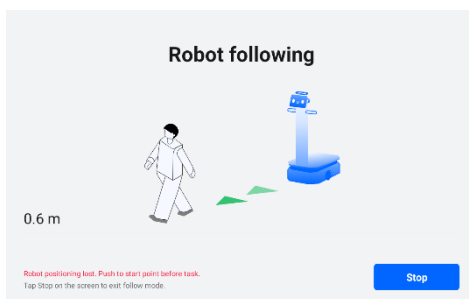
**Step 2** In the robot's searching state, stand in front of the robot and raise one hand. The robot will enter follow mode and follow the designated target object.



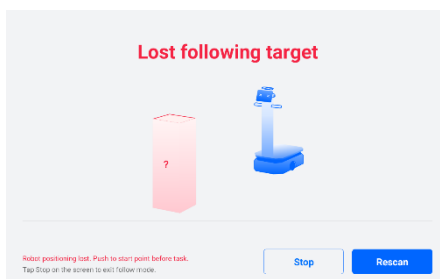
**Step 3** Tap the screen while following the target object to enter the pause state. When paused, stand in front of the robot and tap "Resume" to resume following directly without raising your hand.



Step 4 In follow mode, the robot's interface will display the real-time distance between the robot and the following object. Tap the blue button again or click "Stop" on the screen to exit the follow mode.

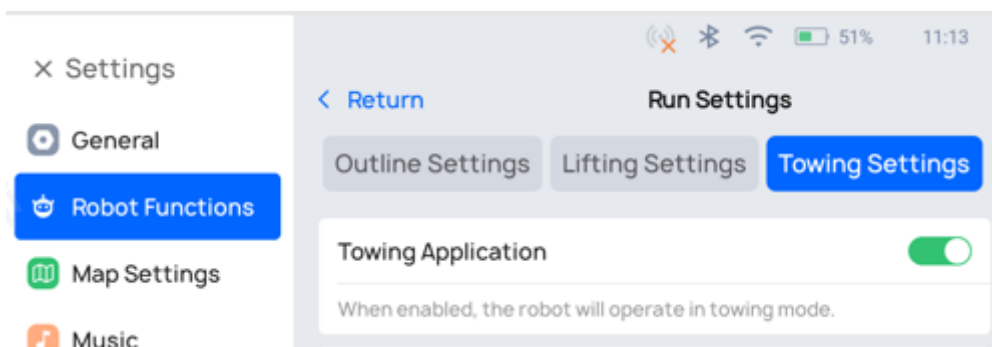


Note: If the following personnel is lost, the robot will announce "Lost following target" At this point, simply stand in front of the robot and raise one hand to allow the robot to follow again.

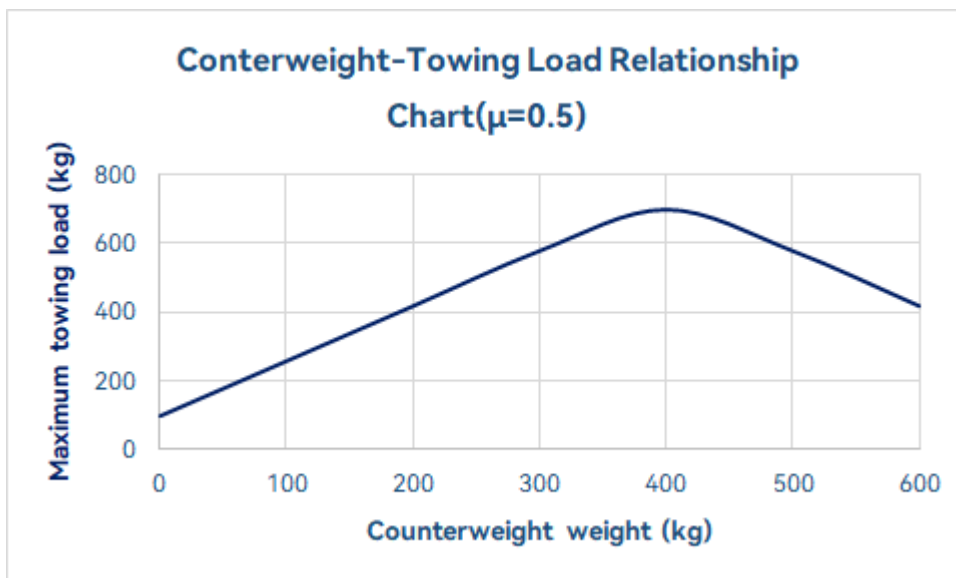


#### 4.3.5.2 Towing Applications

If the robot is equipped with a towing device and the appropriate configuration is done by technical support, the towing application can be activated under "Settings" - "Robot Settings" - "Run Settings".



The towing application allows the robot to transport goods in a towing manner.



As shown in the image above, the T600, with appropriate counterweight, can tow a maximum load of 700 kg (1543.24 pounds).

However, current PUDU towing devices only support a maximum towing load of 400 kg (881.85 pounds). Products supporting larger towing loads are under development.

When equipped with a towing device, the robot can tow and transport goods. Taking the existing towing device with a 400kg (881.85 pounds) load capacity as an example, the robot configuration after installing the towing device is as follow:



① Towing Device: A towing device can be installed on the robot (expected to be available for sale in mid-December). This towing device is compatible with most existing towing hooks used on customer site transport vehicles. After manual attachment, the robot can automatically unload cargo at destination.

② Wire trough. Internally laid out to connect the control cables between the T600 and the towing device.

③ Counterweight area. To ensure sufficient friction between the T600 drive wheels and the ground. Specific counterweight for the robot end.

The software operation steps are as follows:

Step 1 Turn on the main switch for the "Towing Application." Once the main switch is activated, you can configure parameters related to the towing function. With this switch enabled, the robot will take into account the profile of the towing load while performing

delivery and cruising tasks.

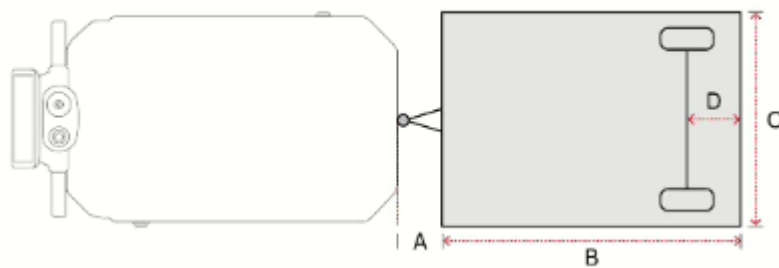
### Towing Setting (mm)

#### Towing Application

☒

When enabled, the robot will operate in towing mode.

Step 3 Configure the type of towing load. Here, you can input the dimensions of all load trailers that will be used with the T600 at the operational site here.



#### Cart1

Towing hook length **A**(0 - 1000)

500

Load Length (including hook) **B**(0 - 5000)

1200

Load Width **C**(0 - 1200)

500

Distance between towing axle and rear **D**(0 - B)

10

Edit

Step 4 Configure the towing scheme. You can freely combine the recorded towing load types to create commonly used towing schemes for the operational site here.

## Towing Plan

PlanB

Cart1 1200x500

Cart1 1200x500

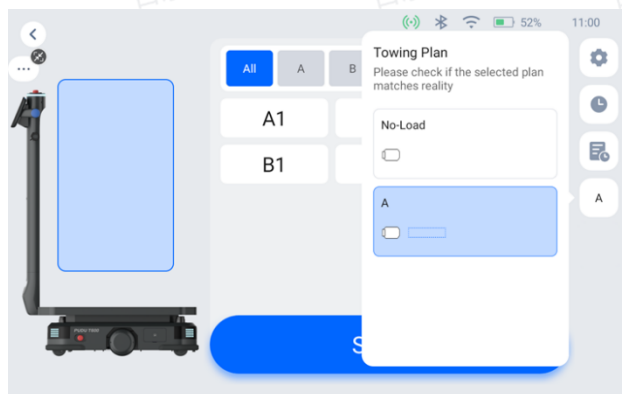
Edit

PlanA

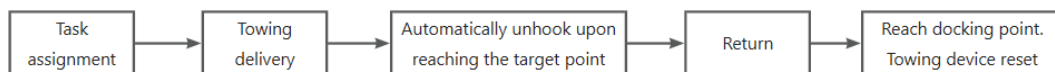
Cart1 1200x500

Edit

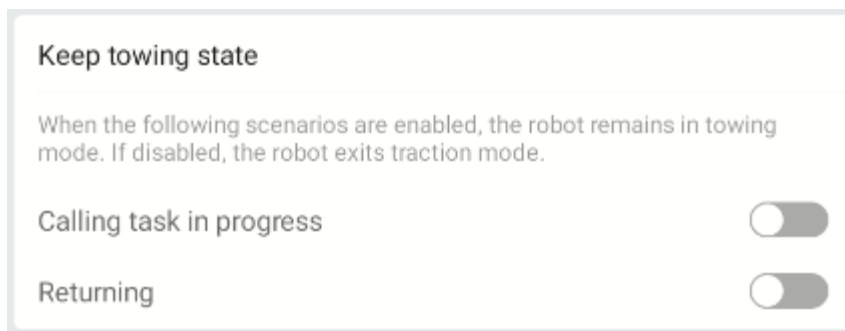
Step 5 Task Assignment. In delivery and cruise mode, before assigning a task to the robot, you need to select both the delivery destination for the robot and the current towing scheme it will use (the last selected scheme will be pre-selected by default). After making your selections, click "Start," and the robot will begin executing the task.



The robot's operating process is as follows:



For your different usage requirements (for example, if you want the robot to remain in towing mode during both the delivery and return journeys), the robot is equipped with a configuration switch that allows you to set whether the robot should maintain towing status during certain processes.



Note: When towing goods, the robot cannot automatically recharge. Therefore, to ensure safety, the robot will disengage the towing mechanism before executing the automatic recharging task.

## 4.4 Setting

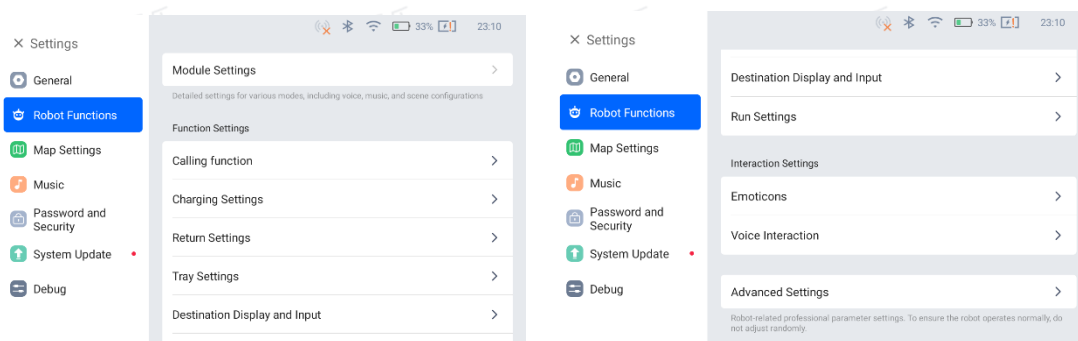
There is a "Settings" button on the robot's homepage. Clicking it will take you to the robot's general settings interface, where you can set the robot's operating configuration.

### 4.4.1 General

In the general settings, you can set basic settings such as language, WLAN, theme, brightness, volume, etc.

### 4.4.2 Robot Functions

The robot function includes most of the robot's operating settings.



The details are as follows:

#### 4.4.2.1 Module Settings

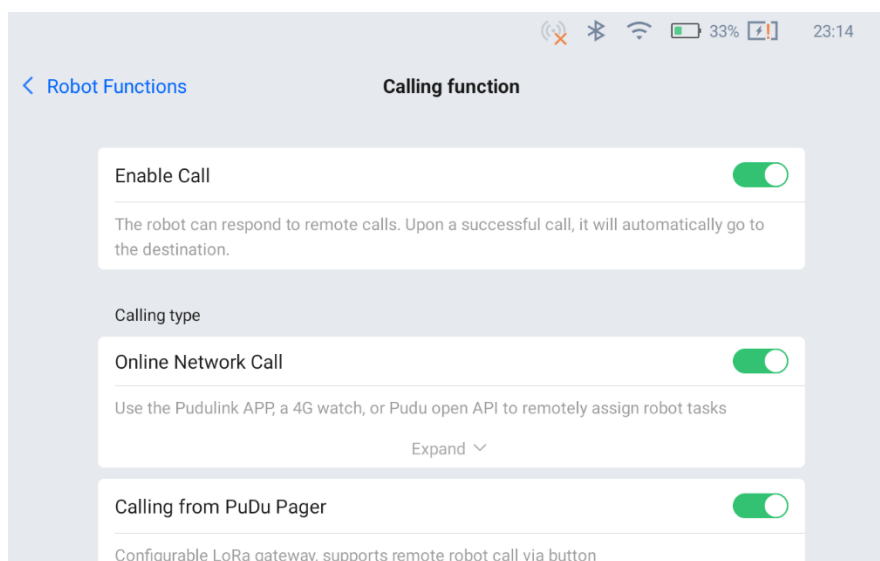
Functions of each business module (same as described in Sections 4.1 to 4.3)

#### 4.4.2.2 Calling function

Remote call related content can be set. Including network call, PUDU pager, microservice, etc.

##### (1) Enable Call

When enable, the robot can respond to remote calls. If you need to use the call function, you can turn on this switch.



## (2) Online Network Call

When the switch is turned on, the robot can call the robot through pudulink APP, 4G watch, open interface and other methods that rely on network links.

## (3) Calling from PuDu Pager

You can configure the PUDU Pager here. For specific deployment methods, please contact technical support.

## (4) Local Microservice

After turning it on, you can use microservice in LAN to call the robot. For specific deployment methods, please contact technical support.

## (5) Other call setting items

Call settings also include the following setting items:

| Setting items            | Description                                                                                                                                                                                                                                                                               |
|--------------------------|-------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| Wait when calling        | When enable, when the robot receives a call task, it will count down according to the set time. And the call task will be executed after the countdown ends.                                                                                                                              |
| Call arrival wait        | When enable, the robot will count down according to the set time after arriving at the point. After the countdown ends, the robot returns to the page before the original call. If this configuration is turned on, it will still stay on the call arrival page after the countdown ends. |
| Call Arrival Jump Mode   | After the robot reaches the target point of the call task, the robot will jump to the corresponding mode;                                                                                                                                                                                 |
| Task complete, returning | After the call task is completed, the robot will return to the set location;                                                                                                                                                                                                              |
| Callable Status          | The state of the robot that can respond to the call task can be set                                                                                                                                                                                                                       |
| Play during tasks        | When enable, you can select the synthesized voice or music file to be played during the call task.                                                                                                                                                                                        |

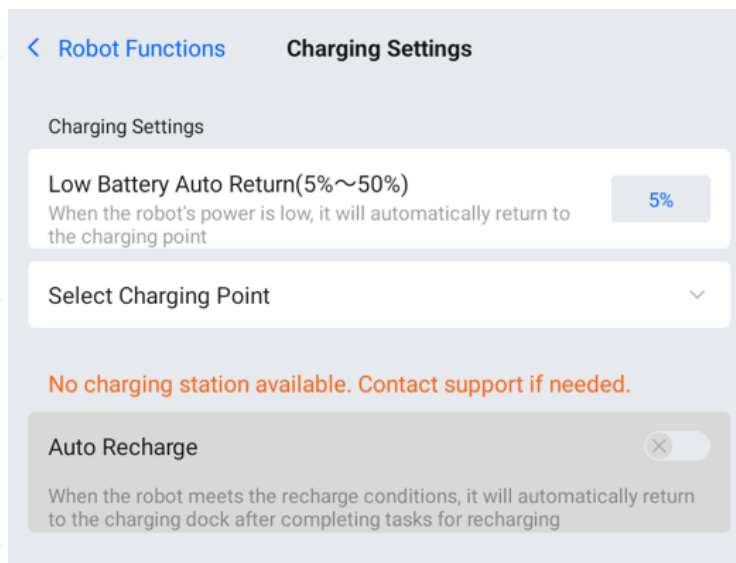
|                 |                                                                                                                             |
|-----------------|-----------------------------------------------------------------------------------------------------------------------------|
| Play on Arrival | When enable, you can select the synthesized voice or music file to be played when the call task arrives at the destination. |
|-----------------|-----------------------------------------------------------------------------------------------------------------------------|

#### 4.4.2.3 Charging Setting

The robot's automatic recharging configuration can be adjusted according to actual usage needs.

(1) When there is no charging point in the map

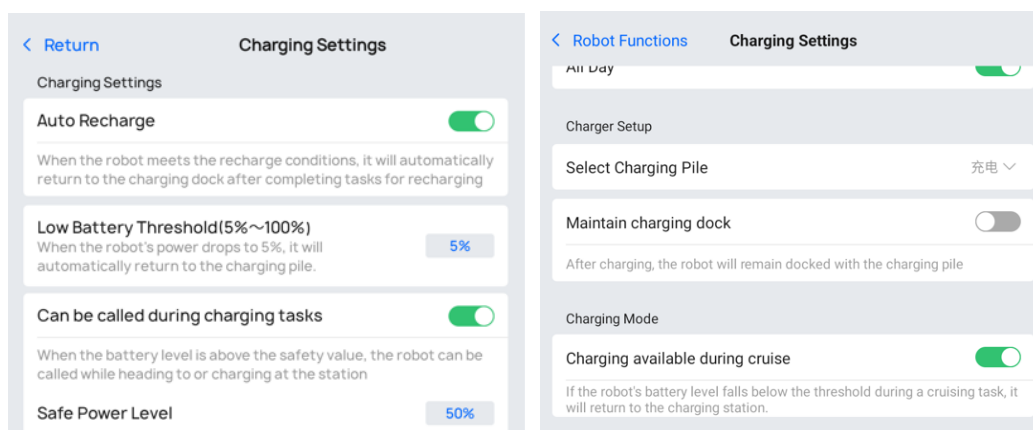
When the robot's map does not contain a charging point, the page displays as follows:



When the robot's battery power is lower than the "low battery Auto Return" threshold, it will automatically return to the charging point. (The charging point is the point where the robot is charged daily, not the location of the charging pile)

(2) When there is a charging pile in the map

When there is a charging pile in the map, the robot will display the following configuration:

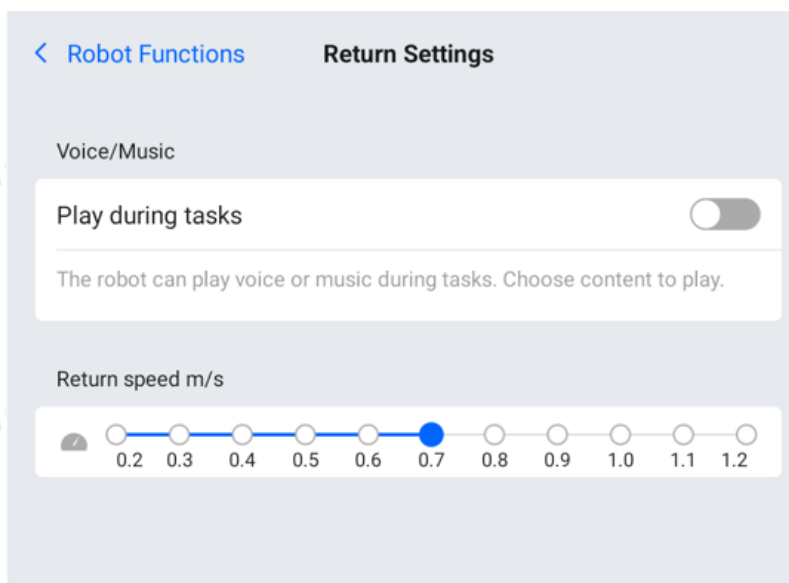


| Setting items | Description |
|---------------|-------------|
|---------------|-------------|

|                                     |                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                      |
|-------------------------------------|------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| Auto Recharge                       | If a charging station is set in the robot map, this switch will be turned on by default.                                                                                                                                                                                                                                                                                                                                                                                                             |
| Low Battery Threshold               | After the switch is turned on, the robot will automatically perform recharging according to the configuration parameters. You can set a power threshold. When the robot power is lower than the threshold (setting range 5%~100%) and the robot is continuously idle. After 1 minute, the robot will automatically perform automatic recharging.                                                                                                                                                     |
| Can be called during charging tasks | After the switch is turned on, when the battery level is above the safety value, the robot can be called while heading to or charging at the station.                                                                                                                                                                                                                                                                                                                                                |
| Automatic charging period           | <p>You can customize the robot's automatic recharge time period. The robot will only perform recharge tasks during the set time period. There is a default "all day" time period in the robot. You can also add time periods by clicking the "+" symbol, and you can turn each time period on/off by using the switch.</p> <p>When multiple time periods are turned on at the same time, the robot will automatically recharge if the current time belongs to any of the time periods turned on.</p> |
| Select Charging Pile                | If multiple charging point are set in the map, you can select the charging station for the robot to automatically recharge here.                                                                                                                                                                                                                                                                                                                                                                     |
| Maintain charging dock              | <p>When this switch is turned off, the robot will automatically return to the standby point after it is fully charged.</p> <p>When this switch is turned off, the robot will stay on the charging pile after it is fully charged.</p>                                                                                                                                                                                                                                                                |
| Charging Mode                       | You can configure whether the robot can automatically recharge in some working states according to actual usage needs.                                                                                                                                                                                                                                                                                                                                                                               |

#### 4.4.2.4 Return Settings

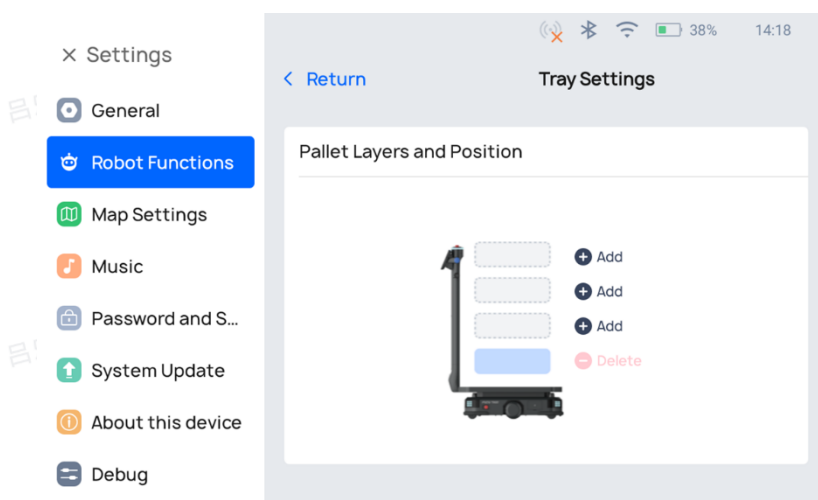
Similar to the mode settings, the return settings include the following settings:



| Setting items     | Description                                                                                               |
|-------------------|-----------------------------------------------------------------------------------------------------------|
| Play during tasks | When enable, you can select the synthesized voice or music file to play during returning.                 |
| Return speed      | The robot's scheduled driving speed in cruising can be configured, with a setting range of 0.2m/s~1.2m/s. |

#### 4.4.2.5 Tray Settings

You can set the robot's load area. This is suitable for use when a pallet or bracket is installed on the robot. After adjustment, the delivery mode page can issue tasks for multiple robot load areas.



#### 4.4.2.6 Destination Display and Input

The destination display and input include the following settings:

| Setting items             | Description                                                                                                         |
|---------------------------|---------------------------------------------------------------------------------------------------------------------|
| Destination column number | You can change the number of columns by selecting different column options for the point list in the delivery mode. |



|                             |                                                                |
|-----------------------------|----------------------------------------------------------------|
| Destination grouping filter | You can also hide certain destination groups in the robot map. |
|-----------------------------|----------------------------------------------------------------|

#### 4.4.2.7 Running Settings

In the running settings, it includes parameter configuration for the general running status of the robot.

| Classification  | Setting items                          | Description                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                             |
|-----------------|----------------------------------------|-------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| Basic Setting   | Automatic resume time paused.          | You can set the countdown duration for the robot's pause state..                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                        |
|                 | Replan path when blocked Configuration | <p>After the switch is turned on, the robot path blockage replanning related configuration will take effect. Under this setting, there are two configurations:</p> <p>Replan route time: When the robot continues to avoid obstacles for the set time, replanning is triggered. At this time, other paths on the map will be selected to try to reach the target point. The setting range is 10~600s, and the default is 30s;</p> <p>Path block lock time: When the robot triggers path replanning, the currently blocked road will be marked as "unavailable". After the time set by this parameter, it will automatically return to the "available" state. The setting range is 30~600s, and the default is 180s.</p> |
|                 | Assist Mode                            | Move heavy-load robots with ease using motor-assisted propulsion and manual light push, enhancing transport efficiency and operational flexibility.                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                     |
|                 | Pause motion only via emergency stop   | Robot motion can only be stopped by pressing the emergency stop button to avoid accidental screen touches pausing tasks.                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                |
| Outline Setting | No load                                | Same as described in section 4.3.                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                       |
| Lifting Setting | Pickup Mode                            | Same as described in section 4.3.                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                       |
| Towing Setting  | Towing Application                     | Same as described in section 4.3.                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                       |

#### 4.4.2.8 Emoticons

Choose whether to display emoticons on the robot during running.

#### 4.4.2.9 Voice Interaction

In the voice interaction module, you can perform the following operations:

Choose the voice speaker for the robot.

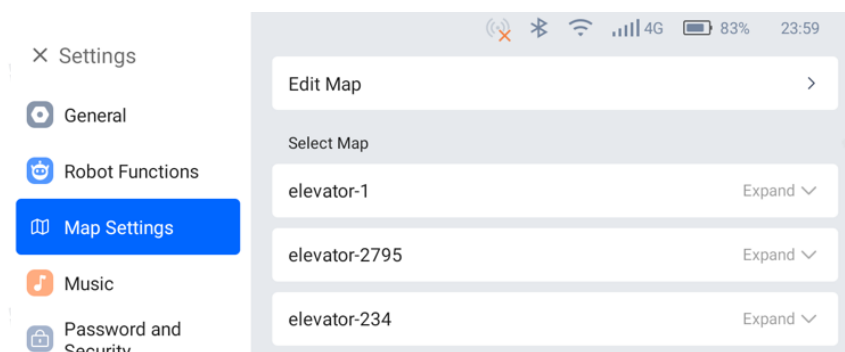
Download voice packages configured on the cloud platform.

Select locally stored voice packages.

#### 4.4.3 Map Settings

The robot can support the configuration of multiple maps, for use when the usage scenario changes or when the scenario route changes. When you switch maps, the Happy Delivery robot will automatically synchronize the destination information, docking location, and other configured information in the maps. Users can select a map and select a robot docking location based on the actual scenario.

Tap on the “Edit Map” screen to access the robot Mapping tool software interface and create maps, edit maps, and more.



#### 4.4.4 Music

In the Music Library module, users can import music for the robot by connecting the robot to the same Wi-Fi as their phone and scanning the QR code in the “Import Music” module. Imported music files will be displayed in the “List of All Music.” The robot can store up to 20 music files.

Supported music file formats: MP3, WAV, FLAC, AAC, PCM.

You can test music by tapping the “▶” button to the right of the music file;

By long pressing a song, the “Delete” button will pop up. Tap the button to delete music.

#### 4.4.5 Password and Security

##### (1) Set Password

In the "Admin Password" section, users can set a 4-digit password. They can also set passwords for different entrances as needed:

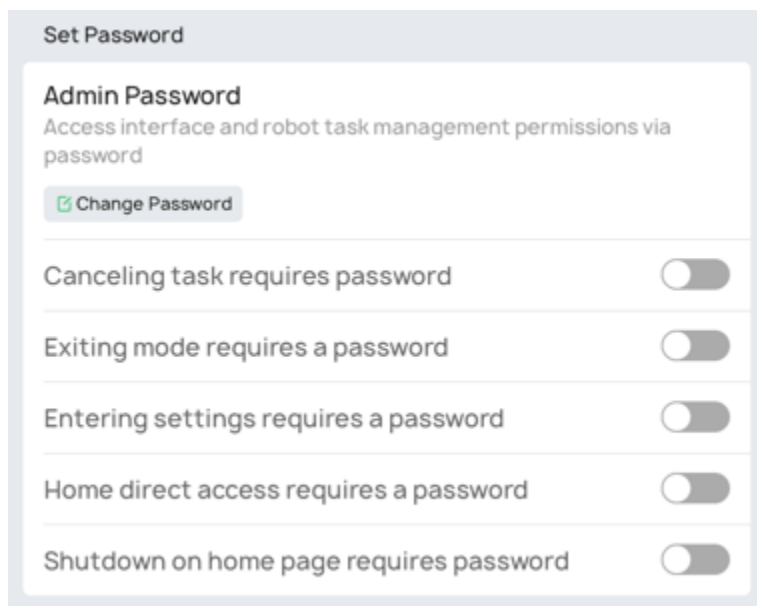
Canceling task requires password: When canceling tasks in various modes, a password is required.

Exiting mode requires a password: When exiting any business mode, a password is required.

Entering settings requires a password: When accessing settings and mode settings, a password is required.

Home direct access requires a password: Clicking on 'Go to xxx' and 'Switch' on the home page requires entering a password before executing the task.

Shutdown on home page requires password: When you click the power switch on the home page, you need to enter a password before the 'Powered off/Restart' page appears.

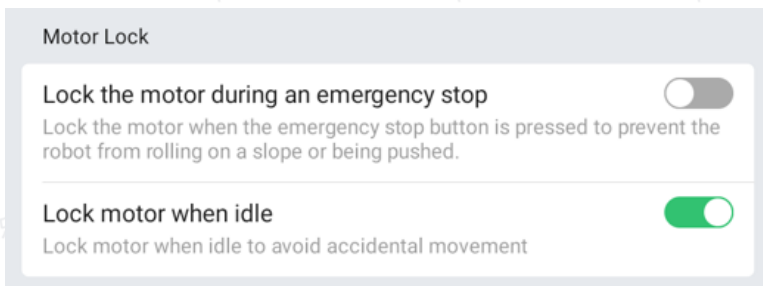


## (2) Motor lock

You can set the time point for locking the robot motors in non-task states.

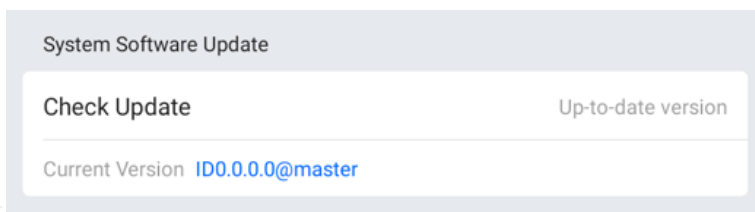
Lock the motor during an emergency stop: After pressing the emergency stop button, the robot locks the motors to prevent accidental movement.

Lock motor when idle: The robot locks the motors when it is in an idle state without any tasks to prevent it from being inadvertently pushed away.



## 4.4.6 System Update

When the robot is connected to the network, it can check whether there are version updates. If a new version of the robot software is available, there will be a red dot prompt next to “System Update” as a reminder to perform the update.



After tapping Update, the robot will download the installation package and a prompt for the download percentage prompt will appear. Once the download is complete for the installation package, the robot will automatically restart.

#### Caution

When performing version updates, please ensure that the robot has at least 20% battery remaining.

Please do not manually turn off the robot while performing a version update.。

#### **4.4.7 Debug**

The Debugging interface is provided for use by technical support to debug the device. Please do not use the Debugging interface yourself.

## 5. Robot Operation

### 5.1 Description of Robot Operation Logic

The robot uses sensors to determine its position within the map. When a task is given to the robot, it will autonomously plan the best path to reach the target location based on the topological path drawn on the map.

As the robot travels along the planned path, it will guide itself to avoid obstacles that are detected but not recorded on the map, in order to prevent collisions between the robot and the obstacles.:

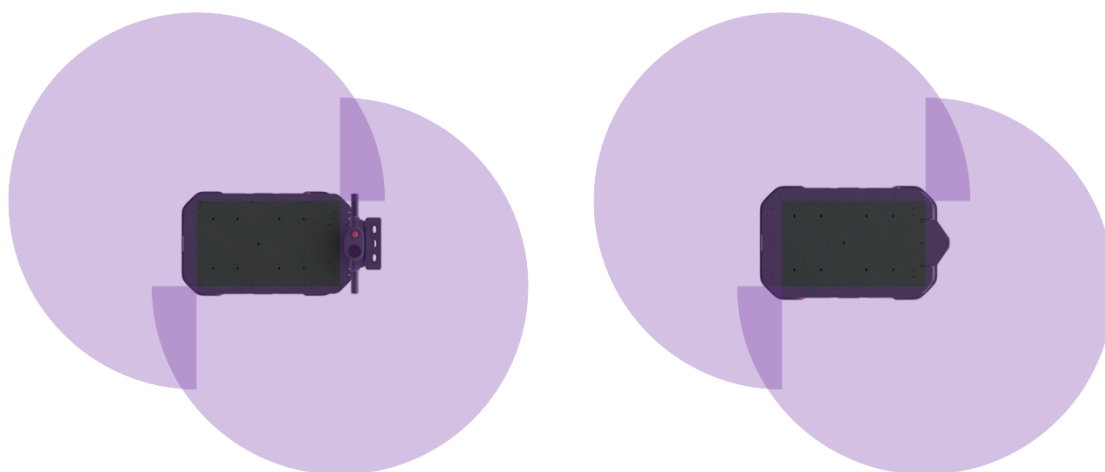
### 5.2 Obstacle Detection

The robot continuously detects obstacles while it is moving to ensure safe operation. The sensors involved in obstacle detection include:

- Lidar
- RGBD
- Collision switches

#### (1) Lidar

The robot scans the surrounding environment using lidars installed at the diagonals of the chassis, achieving a 360° detection around the robot. The specific range is as follows:



Standard version

Underride version

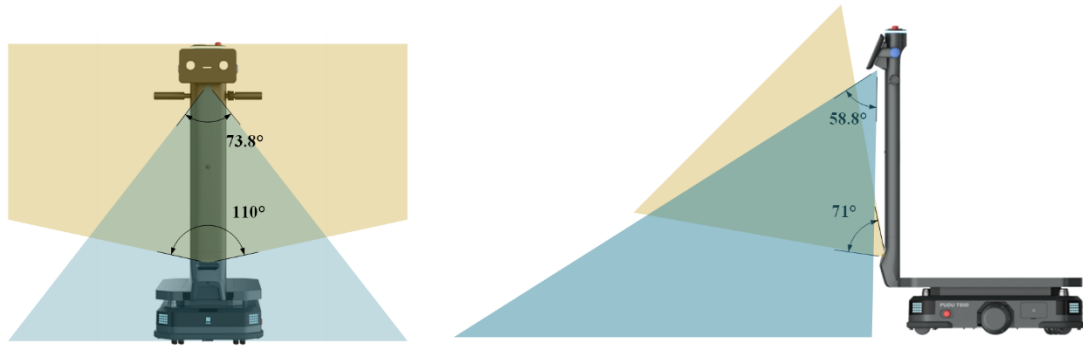
#### ⚠Caution:

The LiDAR can only scan the ground plane at a height of 19cm (7.48inch).

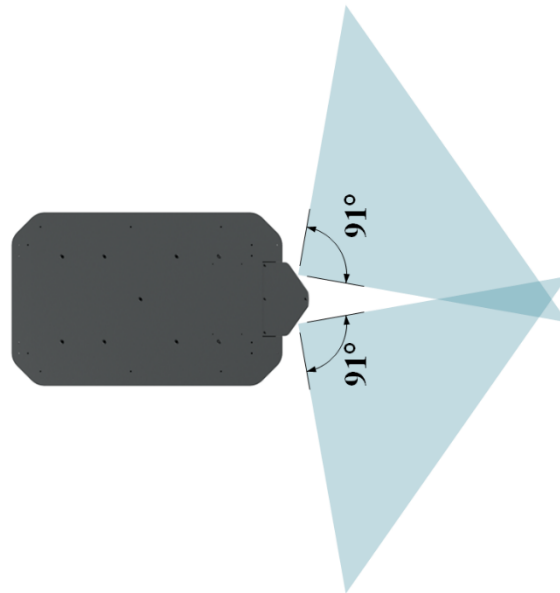
If there are transparent objects (such as glass) or reflective obstacles (such as mirrors) in the environment, the data from the LiDAR may have deviations. It is recommended to place frosted stickers or other markers at a height of 19cm (7.48inch) or set up virtual walls on the map.

#### (2) RGBD

The robot is equipped with two RGBD cameras on the front side, which can perform stereoscopic detection of obstacles in front of the robot. The specific range of detection for the robot is as follows:



Standard version



Underride version

### ⚠Caution

In environments with direct sunlight, the RGBD cameras may have abnormal detection. It is recommended to avoid running the robot in environments with direct sunlight.

If there are transparent objects (such as glass) or reflective obstacles (such as mirrors) in the environment, the RGBD cameras may not accurately detect them. It is recommended to avoid running the robot in such environments or set up virtual walls on the map.

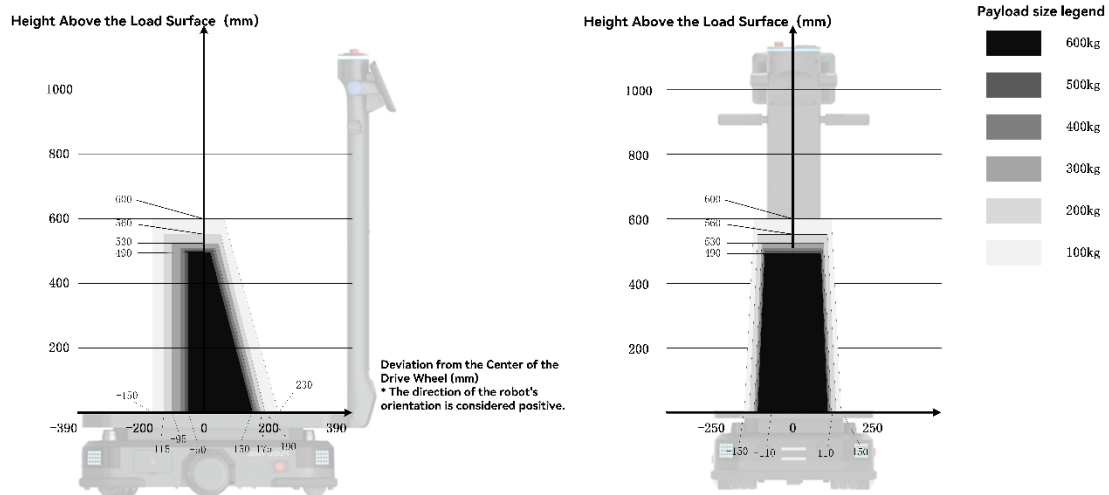
### (3) Collision switches

The collision switches are located at the front and rear edges of the robot's chassis. If the collision sensors are hit during robot operation, the robot will stop moving and pause the task. Follow the instructions on the interface to resume the task.

### 5.3 Safe Center of Mass Distribution for Loads

To ensure the safe and stable operation of the robot during cargo transport, please ensure that the weight distribution of the goods being carried is even. Additionally, the center of gravity of the load must meet the following illustrated requirements.

**Safe Center of Mass Distribution for Loads**



Note: The requirements for the load center-of-mass distribution of the T600 and T600 Underride are identical.

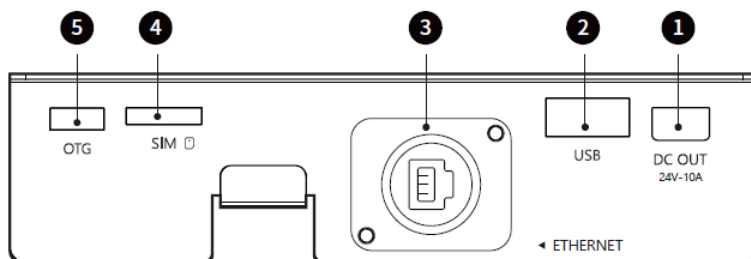
When delivering pallets and racks, supposed the column extended and the load evenly spread across the pallets and racks, the load-bearing capacity on slopes up to 3° is detailed in the table below.

| T600                     | Center of mass offset(mm)    | -80  | -75 | -50 | 0   | 100 |
|--------------------------|------------------------------|------|-----|-----|-----|-----|
| With the column extended | Rack length(mm)              | 1000 | 990 | 940 | 840 | 640 |
|                          | Rack exceeding from rear(mm) | 160  | 150 | 100 | 30  | 0   |
|                          | Max. payload on 3° slope(kg) | 300  | 400 | 600 | 600 | 600 |

| T600                     | Center of mass offset(inch)    | -3.15 | -2.95 | -1.97 | 0.00  | 3.94  |
|--------------------------|--------------------------------|-------|-------|-------|-------|-------|
| With the column extended | Rack length(inch)              | 39.37 | 38.98 | 37.01 | 33.07 | 25.20 |
|                          | Rack exceeding from rear(inch) | 6.30  | 5.91  | 3.94  | 1.18  | 0.00  |
|                          | Max. payload on 3° slope(lb)   | 661.5 | 882   | 1323  | 1323  | 1323  |

## 6. Interface Description

Under the interface window, there are external interfaces that can be used for hardware expansion and device debugging. The specific interface specifications are as follows:



| No. | Name                   | Description                                                |
|-----|------------------------|------------------------------------------------------------|
| 1   | Power supply interface | 24V (battery voltage), maximum output current of 10A       |
| 2   | USB                    | USB 2.0, for data communication with external devices      |
| 3   | ETHERNET               | Network port, for data communication with external devices |
| 4   | SIM card slot          | Supports Nano SIM card                                     |
| 5   | OTG                    | Used for device debugging                                  |

## 7. Troubleshooting

### 7.1 Troubles during Operation

#### Troubles

The following errors may be reported during the robot operation:

- Motor parameters error
- Sensor parameters error
- Sensor connection error
- Motor rotation anomaly

#### Solution

Step 1 Following the prompts on the screen, tap **OK** or **Continue operation** to see if the robot can continue operation.

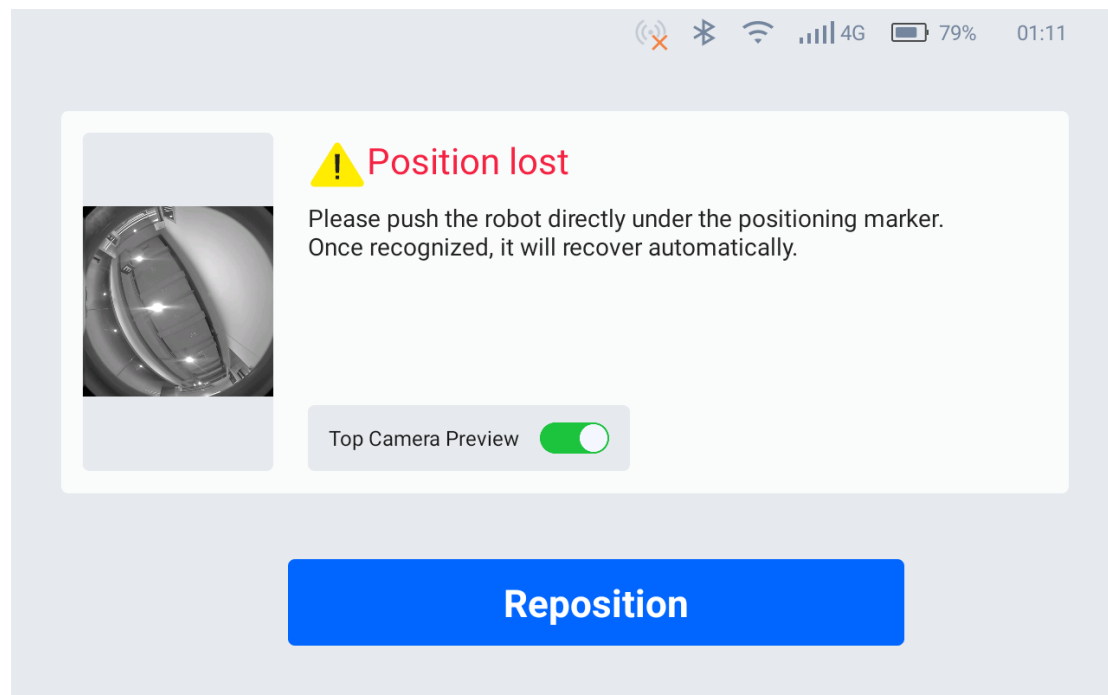
Step 2 If not, reboot the robot and re-enter the task.

Step 3 If the problem persists after the reboot, please contact our technical engineers.

### 7.2 Positioning Failure

#### Troubles

The robot screen prompts **position lost**.



#### Possible Causes

- The robot fails to recognize the positioning feature.
- The map selected on the robot does not match the actual site.

#### Solution

Step 1 If the current map of the robot does not match the actual site, tap **Map selection** to select the correct map of the current site.

Step 2 Check if the robot is directly below the boot point. If the robot deviates too far from the boot point, move the robot right below the boot point. If the problem persists, please adjust the orientation of the robot..

Step 3 Check if the vision sensor is blocked by obstacles such as oil stains. If so, clean it with a lens cleaning kit.

## 7.3Charging Failure

### Troubles

Charging failure

### Solution

- Check if the charger indicator is on. If not, the charging failure may be caused by a damaged charger. Please contact our technical engineers in time.

## 7.4Power-on Failure

### Troubles

Power-on failure

### Solution

- If the battery is low, please charge the robot in time.
- If the problem persists, please contact our technical engineers.

## 7.5Robot Does Not Move Smoothly

### Troubles

The robot does not move smoothly or stops moving.

### Solution

- Check if there are obstacles in front of the robot.
- Check if there are stains like oil or soup on the depth vision sensors.
- Check if the passageway is wider than the minimum travel width.
- Check if there are mirrored and reflective metal surfaces on either side of the passageway that may affect the robot's operation. If so, attach matte stickers 5cm~6cm (1.97inches~2.36inches) above the ground.

## 8. Maintenance and Care

To prevent injuries during operations, debugging and maintenance personnel must wear protective equipment such as safety helmets, safety gloves, and safety shoes when performing maintenance or caring on the robot.

### 8.1 Component Maintenance

| Components                        | Robot Status | Inspection Interval       | Method                                                                                                                                                                                                                                        |
|-----------------------------------|--------------|---------------------------|-----------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| Drive wheels and auxiliary wheels | Powered off  | One week                  | Please wipe the surface with a clean cloth. Check the wheel surface for wear and replace if necessary.                                                                                                                                        |
| Visual sensor, and LiDAR          | Powered off  | One week                  | Please wipe the surface with a clean cloth.<br><br>If there is sudden dirt or damage, please handle it in time to avoid blocking the sensor and causing abnormal operation of the robot.                                                      |
| Robot body                        | Powered off  | One month                 | Please wipe the surface with a clean cloth. And check the installation. Make sure the housing is flat and securely fixed.                                                                                                                     |
| Indicator lights and sound        | Powered on   | One month                 | Check that all indicator lights and audible warnings are working properly.                                                                                                                                                                    |
| Emergency stop switch             | Powered on   | One month                 | Check that the emergency stop button is working properly.                                                                                                                                                                                     |
| Battery                           | Charging     | Three months / Six months | To avoid over-discharged state, battery shall be charged periodically to maintain 20~50% of capacity. Built-in battery shall be charged with terminal every 3 months while removable battery shall be charged every 6 months are recommended. |
| Brake switch                      | Powered on   | Six months                | Put the brake switch to the "OFF" position and gently push the robot forward to check that the brake switch is working properly.<br><br>Note: Turn the brake to the "ON"                                                                      |

|                                |             |            |                                                                                                   |
|--------------------------------|-------------|------------|---------------------------------------------------------------------------------------------------|
|                                |             |            | again after checking.                                                                             |
| Safety stickers and nameplates | Powered off | Six months | Check that the safety stickers, labels and nameplates on the robot are intact and clearly visible |

## 8.2 Cleaning Method



### Warning

Do not use water or any other liquid to clean the robot. Always make sure that the robot is kept dry.

Step 1 Press and hold the power switch for 3 seconds to ensure that the robot is powered off.

Step 2 Wipe the robot surface with a clean cloth.

Step 3 Wipe the chassis, drive wheels, and auxiliary wheels with a clean cloth.



### Note

- If the drive wheels or auxiliary wheels are entangled or stuck with debris, please place the robot down on its side for cleaning. Keep the ground clean and tidy (a mat can be used) to avoid scratches on the robot surface when placing the robot down on its side.
- If there are oil stains on the tray pad, take it out and wash it separately. Put back the tray pad after it dries off completely.

Step 4 Clean the vision sensor, depth vision sensors, and Lidar with a clean cloth or specialized lens cleanser.



### Note

- In case of unexpected contamination, address it immediately to avoid blocking the sensor and preventing the robot from working improperly.

## 9. Compliance Information

### 9.1 Federal Communications Commission Compliance Statement

The following information applies to Pudu robotic.

This equipment has been tested and found to comply with the limits for a Class B digital device, pursuant to part 15 of the FCC Rules. These limits are designed to provide reasonable protection against harmful interference in a residential installation. This equipment generates, uses and can radiate radio frequency energy and, if not installed and used in accordance with the instructions, may cause harmful interference to radio communications. However, there is no guarantee that interference will not occur in a particular installation. If this equipment does cause harmful interference to radio or television reception, which can be determined by turning the equipment off and on, the user is encouraged to try to correct the interference by one or more of the following measures:

- Reorient or relocate the receiving antenna.
- Increase the separation between the equipment and receiver.
- Connect the equipment into an outlet on a circuit different from that to which the receiver is connected.
- Consult the dealer or an experienced radio/TV technician for help.

This device complies with Part 15 of the FCC rules. Operation is subject to the following two conditions:

- This device may not cause harmful interference.

This device must accept any interference received, including interference that may cause undesired operation.

### 9.2 Industry Canada Compliance Statement

This device complies with Industry Canada licence-exempt RSS standard(s). Operation is subject to the following two conditions:

- This device may not cause interference.
- This device must accept any interference, including interference that may cause undesired operation of the device.

### 9.3 Disposal and Collecting Information



The Waste Electrical and Electronic Equipment (WEEE) Directive aims to minimize the impact of electrical and electronic goods on the environment, by increasing re-use and Collecting and by reducing the amount of WEEE going to landfill. The symbol on this product or its packaging signifies that this product must be disposed separately from ordinary household wastes at its end of life. Be aware that this is your responsibility to dispose of electronic equipment at Collecting

centers in order to conserve natural resources. Each country should have its collection centers for electrical and electronic equipment Collecting. For information about your Collecting drop off area, please contact your related electrical and electronic equipment waste management authority, your local city office, or your house hold waste disposal service.



Before placing electrical and electronic equipment (EEE) in the waste collection stream or in waste collection facilities, the end user of equipment containing batteries and/or accumulators must remove those batteries and accumulators for separate collection.