

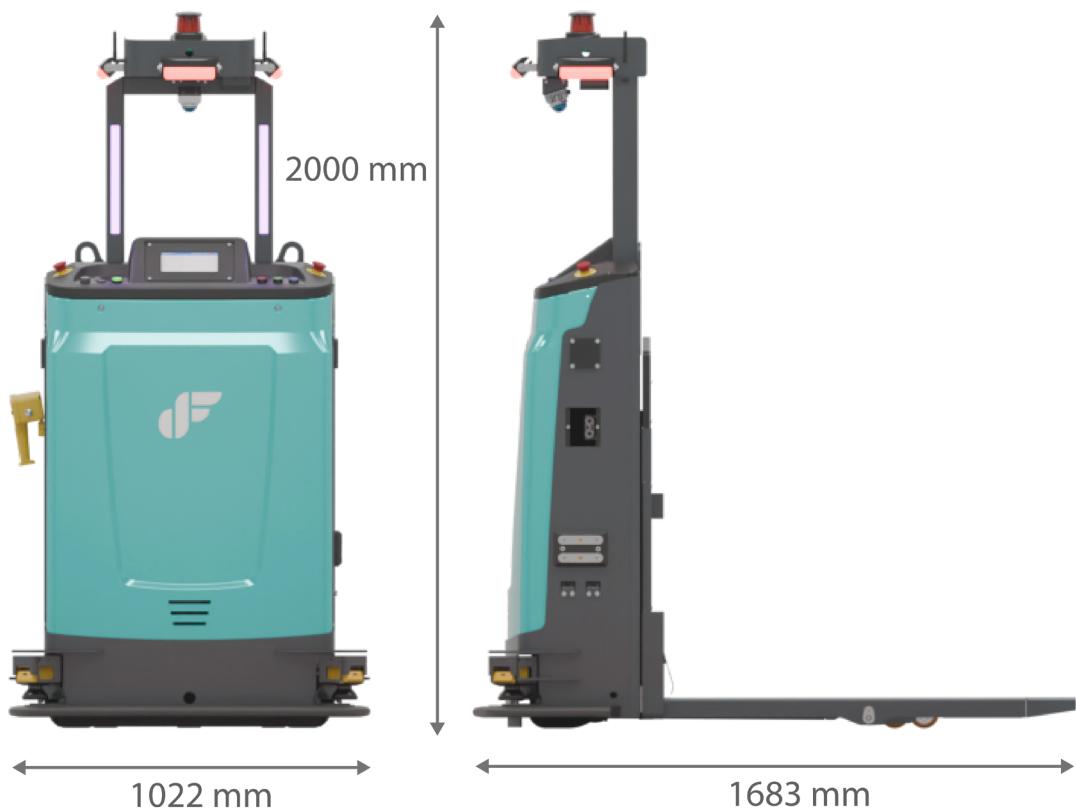


**AUTONOMOUS MOBILE ROBOT**  
**ZETHA**



@dfautomation

## AMR BASE



## HIGHLIGHTS

Powered by DF Navwiz and  
DFleet Software



Advance 3D Camera technology

3D LiDAR Detection



Up to 1.5 m/s  
speed



Carry up to  
2000 kg

LifePo4 Battery  
Up to 8 Hours continuous operation



## ACCESSORIES

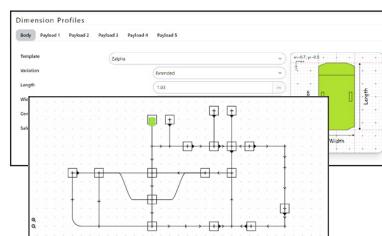


## 3000W Standard Charging Station

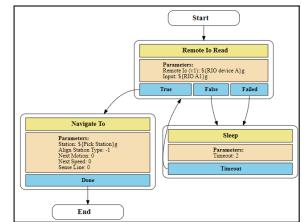
## AMR OPERATING SYSTEM



## Mapping & Navigation



## User Editor & Interface

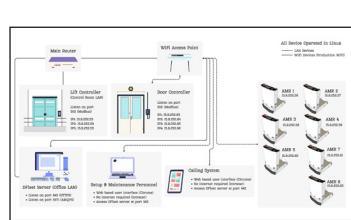


## Flow Chart Programming

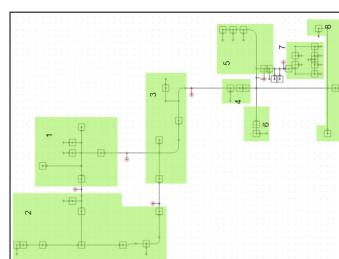
# FLEET MANAGEMENT SYSTEM



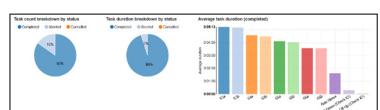
## AMR Traffic Control & System Integration



### 3<sup>rd</sup> Party Integration



## Traffic Control



## Reports & Analytics

# SPECIFICATIONS

## GENERAL

Base Dimension	L: 1683mm x W: 1022mm x H: 2000mm
Carry Payload	2000kg
Lifting Height	110mm
Fork Dimension	L: 1150mm x W: 175mm x H: 56mm
Fork Outside Spread	650mm

## DRIVING & NAVIGATION

Driving System	Steering Drive
Navigation System	Natural Feature Navigation • Optional marker for precision

## PERFORMANCE

Maximum Speed	Unladen: 1.5m/s (5.4km/h) Laden: 1.2m/s (4.3km/h) • Travelling max speed is recommended to undergo Risk Assessment as well
Stopping Accuracy	Laser Sensor (Natural Feature): $\pm 50$ mm, $\pm 2^\circ$ Laser Sensor (Marker/Docking): $\pm 10$ mm, $\pm 1^\circ$
Maximum Gradeability	5% (2.86°) • Without curb • With rated payload • Permissible ramp is to ensure safety, although robot might be able to climb ramp with more than stated value but doing so will jeopardize robot's safety compliance

## SAFETY

Emergency Switch	2 Units
Protective Devices	2D Obstacle Laser Scanner x2 3D Obstacle Laser Scanner Physical Bumper Fork IR Sensor x2 3D Camera
Indicator	RGB LED Lighting Music Playback & Alarm

## INTERFACE

Language	English
Operating System	Standalone (NavWiz) / Fleet Management System (DFleet)
Screen	7", 1024x600 IPS HDMI Capacitive Touch Monitor
Communications	802.11 a/b/g/n, 2.4GHz / 5GHz WiFi Open WiFi WPA & WPA2 Personal WPA & WPA2 Enterprise

\*Specifications may vary and are subject to revisions

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