

Hermes

General Purpose Robot Platform

User Manual

- Small- to medium-sized robot development
- Highly adaptable and scalable
- Powerful optional functions

[Learn more >](#)



Contents

| | |
|--|-----------|
| 1.INTRODUCTION | 4 |
| 2. INTRODUCTION TO HERMES FEATURES..... | 5 |
| 2.1Autonomous Path-Finding | 5 |
| 2.2Robot Collaboration | 5 |
| 2.3Cross-Floor Delivery | 5 |
| 2.4Smart Obstacle Avoidance | 5 |
| 2.5Comprehensive Safety | 5 |
| 2.6Autonomous Recharging..... | 5 |
| 3. HERMES SCHEMATIC DIAGRAM | 6 |
| 4. HERMES CHARGING STAND | 7 |
| 5. PARAMETERS | 8 |
| 6. INSTRUCTIONS OF HARDWARE | 11 |
| 6.1 Wire Instructions | 11 |
| 6.2 Important Interfaces of Developing Board on RK3399 | 14 |
| 6.3 Reference of Hardware Design..... | 14 |
| 7. REFERENCE OF STRUCTURE DESIGN..... | 25 |
| 7.1 Installing Interface of Host Computer..... | 25 |
| 7.2 Instruction of Load Limit | 25 |
| 7.3 Radar Clearance Area | 26 |
| 7.4 Deep Camera Clearance Area..... | 27 |
| 7.5 Instruction of Transport Design | 27 |
| 8. SETUP INSTRUCTIONS | 29 |
| 8.1 Opening | 29 |
| 8.2 Placing Charging Base | 29 |
| 8.3 Power ON/OFF | 30 |
| 8.4 Charging | 30 |
| 8.5 Emergency stop & brake and reset..... | 30 |
| 8.6 Map Building and Upload | 31 |

| | |
|---|----|
| 8.7 Host Computer Completes Startup and Loading The Map | 34 |
| 9. CONNECTION TO COMPUTER | 36 |
| 10. ADJUSTING TOOLS..... | 39 |
| 10.1 RoboStudio..... | 39 |
| 10.2 Web Management Backstage | 39 |
| 11. DEVELOPER TOOLS..... | 40 |
| 11.1 Start Using..... | 40 |
| 11.2 Inter-system Adjusting Framework | 40 |
| 11.3 Instructions of Each System..... | 40 |
| 11.4 Demonstrations of Code | 42 |
| 11.5 Details Of Robot API | 44 |
| 12. INTRODUCTION AND USE OF ELEVATOR CONTROL..... | 46 |
| 12.1 Introduction | 46 |
| 12.2 Features | 46 |
| 13. SPECIAL NOTE..... | 48 |
| 13.1 Charge point deployment | 48 |
| 13.2 Restricted usage scenarios..... | 48 |
| 13.3 Faults that cannot be handled temporarily | 49 |
| 13.4 Notes..... | 49 |
| 14. MAINTENANCE | 51 |
| 15. COMMON FAULTS AND TROUBLESHOOTING | 52 |
| 16. PRODUCT EXECUTIVE STANDARDS AND CERTIFICATES..... | 53 |
| 16.1 Product executive standards | 53 |
| 16.2 Certificate | 53 |

1. Introduction

Developed by Slamtec, Hermes is a scalable and low-cost robot platform capable of meeting the needs of small-to medium-sized robot application development in areas such as smart patrol robots, container transportation robots, hotel delivery robots, food delivery robots, and more.

Autonomous Localization and Navigation

The built-in SLAMCUBE autonomous localization and navigation system kit enables path-finding and localization and navigation features to help robots figure out where they are, where they should go, and the best way to get there. Hermes is capable of performing a variety of tasks across different commercial environments.

Multi-Sensor Data Fusion

Multi-sensor data fusion technology is an effective way to improve the sensing capability of robotic systems. Hermes uses multi-sensor data fusion technology to effectively realize high degrees of autonomy and awareness in unpredictable environments. Fitted with equipment such as lidar, magnetic sensors, depth cameras, and bumper sensors, Hermes can implement autonomous mapping, localization, and navigation by flexibly responding to complex and ever-changing operational environments.



2. Introduction to Hermes Features

2.1 Autonomous Path-Finding

The built-in SLAMCUBE autonomous localization and navigation system kit enables path-finding and localization and navigation features to help robots figure out where they are, where they should go, and the best way to get there. Hermes is capable of performing a variety of tasks across different commercial environments. Hermes is capable of autonomous localization and path-finding in accordance with task target points, implementing autonomous movement.

2.2 Robot Collaboration

Hermes supports multi-robot collaboration to meet the needs of multi-task operations in complex environments during peak periods. Hermes supports local area network (LAN) and cloud platform collaborative operations, along with the dynamic adjustment of both speed and delivery routes in accordance with the environment to realize efficient, safe, and reliable multi-point delivery.

2.3 Cross-Floor Delivery

The Smart Elevator Control 3.0 system provides accurate detection of elevator statuses along with call-control functionality to provide efficient and reliable solutions that help hotel delivery robots autonomously navigate elevators in cross-floor scenarios. Through our API interfaces, Smart Elevator Control 3.0, as a relatively independent set of solutions, can also be integrated with other smart devices or third-party applications to meet the differentiated customization needs of customers.

2.4 Smart Obstacle Avoidance

The multi-sensor fusion technology of Hermes provides rapid and accurate identification of surrounding active environments, enabling smart obstacle avoidance and greatly reducing the chances of safety incidents.

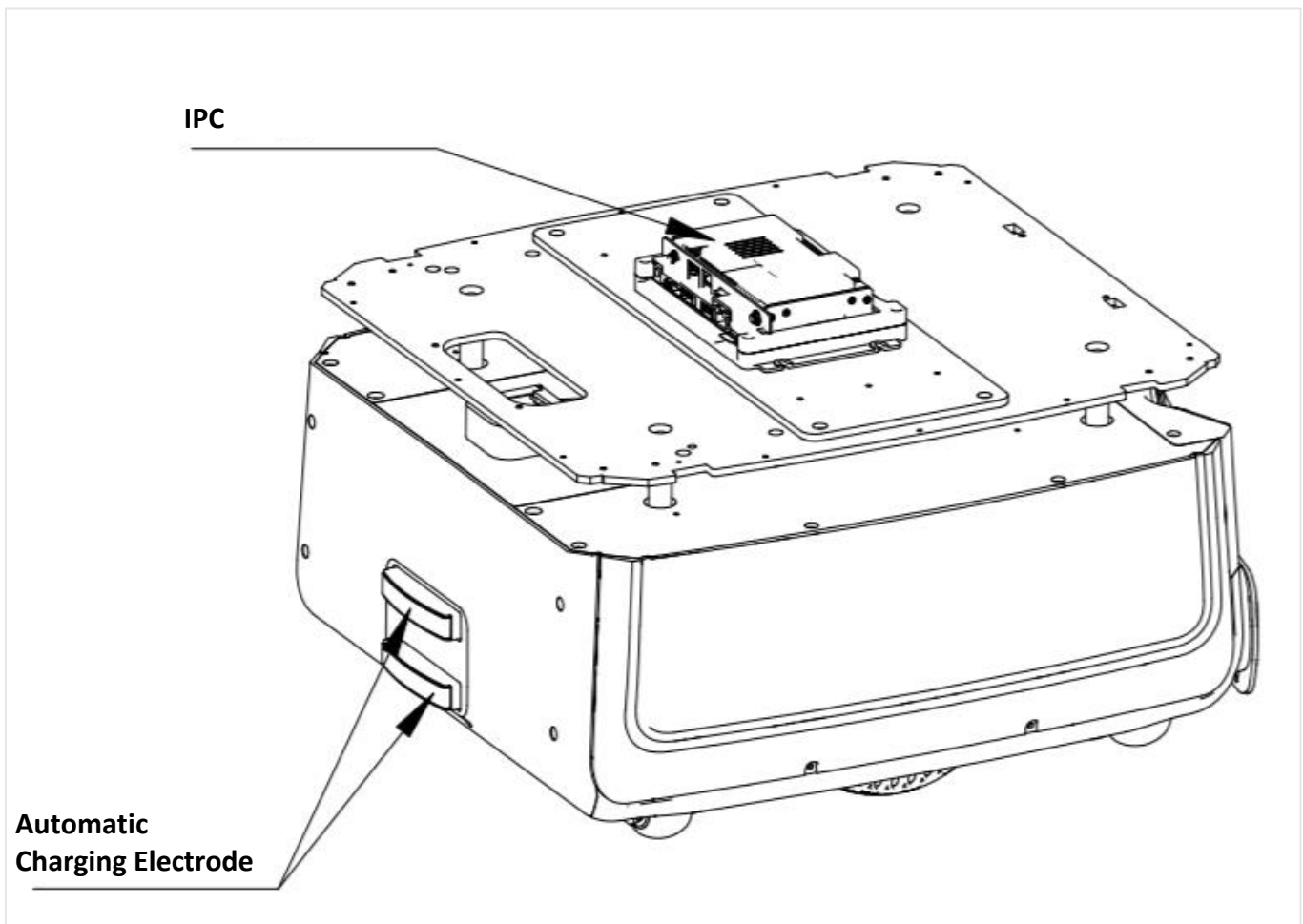
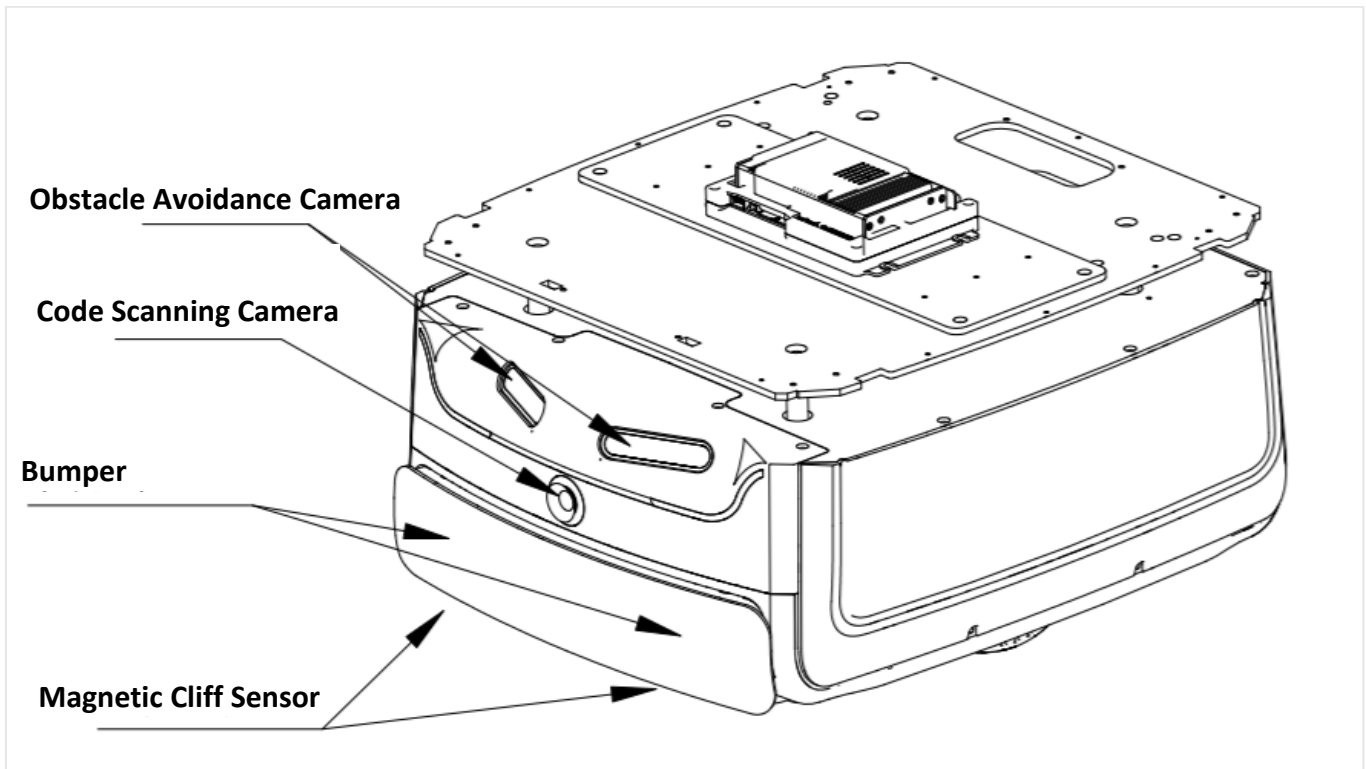
2.5 Comprehensive Safety

Hermes uses multi-sensor fusion methods such as dual-depth magnetic sensors, bumper sensors, and lidar to accurately identify and avoid both moving and static obstacles. The robot also supports fall avoidance, collision avoidance, and emergency braking functionality to ensure comprehensive safety during the move process.

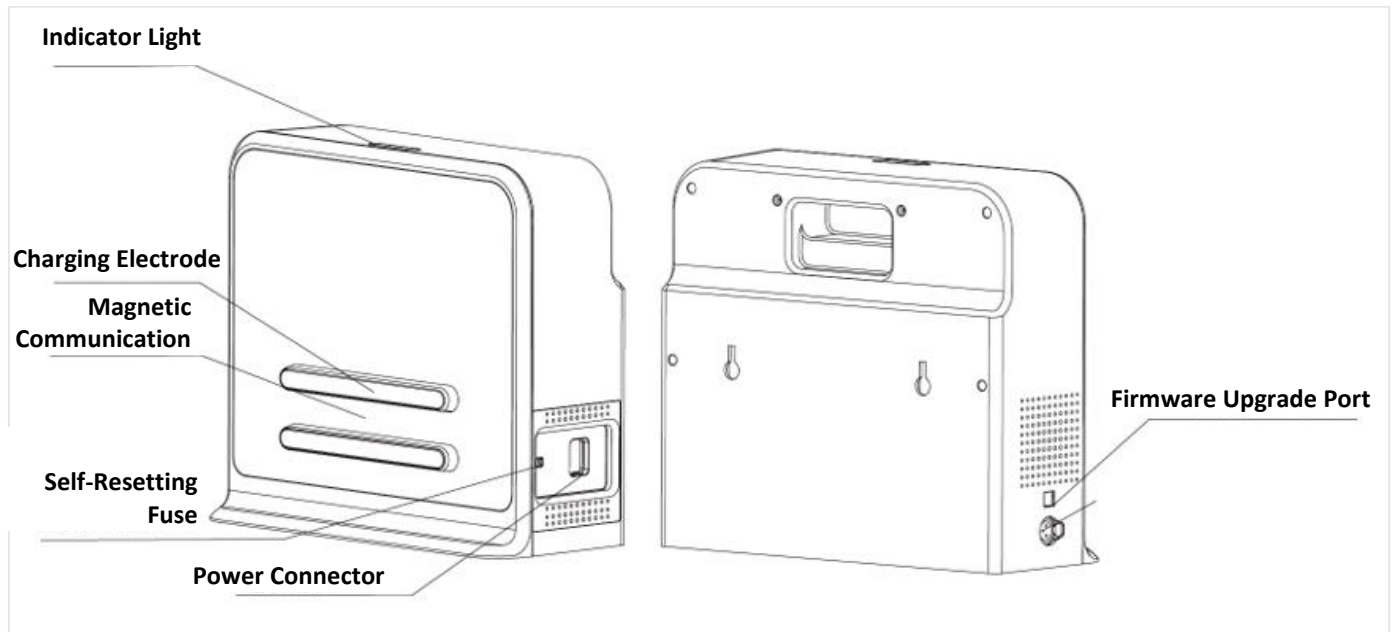
2.6 Autonomous Recharging

Sufficient power is ensured for Hermes to complete assigned tasks smoothly. Hermes automatically returns to the charging station when its battery charge falls below a configured threshold or when its tasks are completed.

3. Hermes Schematic Diagram



4. Hermes Charging Stand



5. Parameters

| Name | | Hermes | |
|-------------------------------|---------------------|--|---|
| Core Features | | SLAM Localization and Navigation | |
| Item | | Index | Value |
| Mass and Volume | | Length x Width | 545 x 465 mm |
| | | Height | 272 mm (excludes controller) |
| | | Weight | 40 kg (excludes controller) |
| | | Rated load | 50 kg |
| | | Max load (parallel cement pavement) | 80kg |
| Sensor Performance Parameters | Lidar Sensor | Max Scan Radius (90% Surface Reflective Rate) | 30m, 360° |
| | Depth Camera Sensor | Quantity | 2 units |
| | | Detection Range | 0.2m-10m |
| | | Field of View (FOV) | Single H:58.4° V:45.5° Double H:126° V:45.5° |
| | Boundary Sensor | Quantity | 2 units |
| | | Max Detection Range | 3.5cm |
| | Bumper Sensor | Quantity | 2 units |
| | | Trigger Method | Physical Collision |
| Mapping Performance | | Map Resolution | 5 cm |
| | | Max Mapping Area | 500m x 500m |
| Motion Parameters | | Max Move Speed | 1.0m/s (Can be customized1.2 m/s) |
| | | Max Cross Slope | 10° |
| | | Passing Obstacle Height | 2 cm |
| | | Passing Obstacle Width | 4 cm |
| | | | |





| | | | |
|-----------------------|---------------|----------------------------------|--|
| User Port | Hardware Port | Ethernet | 1x RJ45 Gigabit Ethernet Port |
| | | Power Connector | DC 24V 9.5A DC12V 2A |
| | | Wi-Fi | 2.4 GHz |
| | | 4G | 1x 4G |
| | | SIM card slot | 1 unit |
| | | HDMI | 1x HDMI |
| | | Audio | 1x 3.5mm Headset Socket 1x LINE_MIC Audio Jack (Co-lay with headset socket) 1x Dual-Channel 5w/8Ω Amplifier Jack |
| | Type-C | Standard USB 3.0 Type-C Port | |
| Software API | | SLAMWARE™ | / |
| Battery and Capacity | | Capacity Specifications | 16 Ah (Standard) 25 Ah (Optional) |
| | | No-Load Operating Time | 9.5h (16Ah) 15h (25Ah) |
| | | Charging Time | 3h-4h |
| | | Battery Life | 500 charges |
| Power Consumption | | Standby power consumption | 32W (16Ah, No-load) |
| | | Motion power consumption | 39W (No-load) |
| | | Full load power consumption | 32W (Standby) 62W (Motion) |
| | | Maximum access power consumption | 228W |
| | | Rated output | DC25.5V 2A |
| Wheelset | | Wheelset Parameters | 6.5-inch In-Wheel Motor |
| Noise | | Working noise | ≤60dB |
| Operating Environment | | Operating Temperature | 0°C to +40°C |

| | | |
|--|---------------------------------------|----------------------------------|
| | Transportation and storage conditions | -25 °C to +55°C |
| | Operating Humidity | 30 to 70%rh (no condensation) |
| | Height above sea level | ≤2000m |

| Charging point | |
|-----------------------|-------------------------|
| Name | Parameters |
| Size | 360mm*150mm*320mm |
| Color | White |
| Rated input | 100-240V 50/60Hz 3A MAX |
| Rated output | DC 25.5V 6A |
| Rated input frequency | 50/60Hz |

6. Instructions Of Hardware

6.1 Wire Instructions

| Interfaces | Picture | Index | Function | Note |
|------------------------------|---|--|--|--|
| Power ON/OFF |  | -- | Power switch of the entire system. Short press until the indicator light turns on power-on, long press until the indicator light turns off power-off. | -- |
| Shut Down |  | -- | Effectively control Hermes in an emergency. After pressing, Hermes will immediately shut down. | It is a switch that must be designed according to rigid regulations. If the switch is not designed, Hermes will refuse to run. |
| Brake |  | -- | When robot is energized, press this switch to release the brake and you can push the robot freely; press it once again to brake, and the robot will not be able to push it freely. | Invalid if the robot is not turned on |
| 24V Power |  | Rated Voltage 24V Maximum current 9.5A | Maximum output power is 200W, can be used to supply power to external devices | No overload |
| 12V RK3399 Power Supply Wire |  | Rated Voltage 12V Maximum Current 20A | Cube2 supplies power to the RK3399 development board. | |

| | | | | |
|------------------------|---|--|--|---|
| Depth Camera Interface |  | USB3.0 | Connected to the RK3399 development via USB3.0 to obtain information. | Need to pay attention to the left and right sequence. |
| Docking Camera |  | USB2.0 | Connected to the RK3399 development via USB3.0 to obtain information of code scanning camera. | Assist precise docking. |
| 12V -DISP |  | Rated Voltage 12V (See the figure below for the design drawings) | 12V working power of Cube2 to provide the external display screen of human-computer interaction. | Maximum current 2A |
| USB-Type-C |  | USB3.0 | Used for communication between 3399 and Cube2. | Connect to Hub3.0 |

Design drawing of 12V -DISP terminal

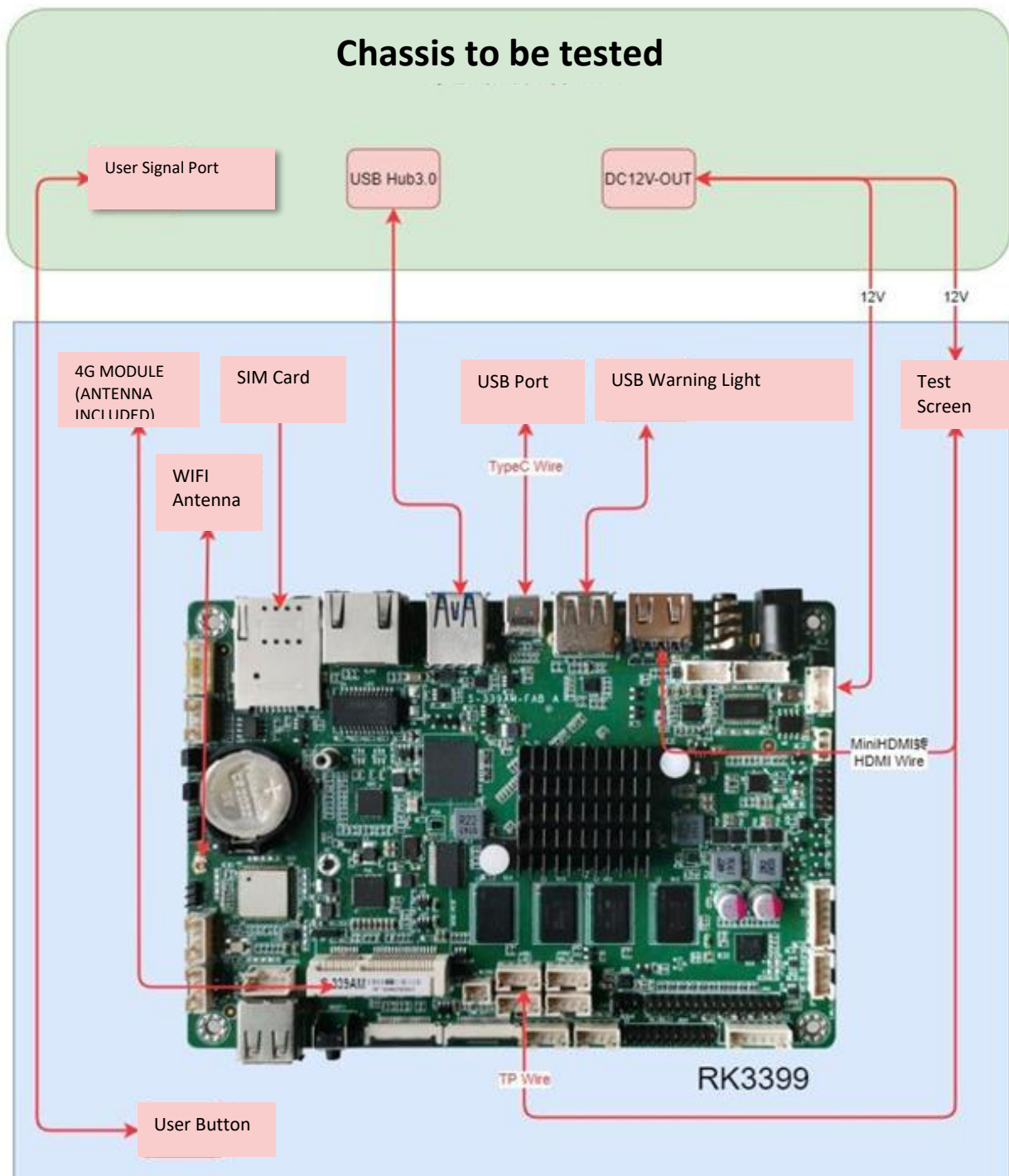
| ECN NO. | | REV | REVISIONS DESCRIPTION | APPVD | DATE |
|---------|--|-----|-----------------------|-------|------------|
| | | A/0 | INITIAL RELEASE | ***** | 2021.06.08 |

接线表

| 颜色 | P1 | P2 |
|----|----|----|
| 红 | 1 | 2 |
| 黑 | 2 | 1 |

| | | | |
|---|--------------|------------|-------------------|
| 产品符合RoHS要求 **This product conforms RoHS environmental requirements** | | | |
| 上海思岚科技有限公司 Shanghai SLAMTEC Co., Ltd. | | | |
| ⑤ | | | 思岚料号 P/N |
| ⑥ | | | 产品名称 TITLE |
| ⑦ | | | 12V-DISP |
| ⑧ | | | 图号 DWG NO. |
| ⑨ | | | Mry2-L04-003 |
| ⑩ | | | 外部料号 P/N |
| ⑪ | | | 一般公差 TOLERANCE |
| ⑫ | SI-2P | 1 | PCS |
| ⑬ | PI-2Y | 1 | PCS |
| ⑭ | UL1007 22AWG | 1 | PCS |
| ⑮ | 材料规格 SREC | 用量 Q'TY | 单位 UNIT |
| ⑯ | | | 备注 |
| ⑰ | | | 核准 APPROVED |
| ⑱ | | | 版次 REV. |
| ⑲ | | | A/0 |
| ⑳ | | | 比例 SCALE |
| ㉑ | | | FREE |
| ㉒ | | | 公差 TOLERANCE |
| ㉓ | | | X ±0.5 |
| ㉔ | | | X.X ±0.3 |
| ㉕ | | | X.XX ±0.1 |
| ㉖ | | | X.XXX ±0.05 |
| ㉗ | | | X' ±2' |
| ㉘ | | | X.X' ±1' |

6.2 Important Interfaces of Developing Board on RK3399



6.3 Reference of Hardware Design

Notice:

- (1) Before starting, please read the manual carefully to avoid product damage caused by misoperation;
- (2) The working temperature of the main board is 0°C to +40°C, 30%-70%RH, in order not to damage the product due to excessive cold/heat or moisture;

(3) Do not make strong mechanical movement of this product, and operate this product before static protection is done;

(4) Please turn off the power before installing any external cards or modules;

(5) Please ensure the external power supply is DC 12V to avoid damage to the main board;

6.3.1 Product Description

RK3399 Android system main board adopts Rockchip RK3399 main control solution. The specification of the main board is a standard 3.5-inch structure with a size of 146*102mm.

The main board processing core RK3399 is based on the dual Cortex-A72+four Cortex-A53 core CPU structure. It uses the powerful Mali-T864 GPU graphics display core, supports VP9, H.265/H264 hardware decoding, and 4K ultra high-definition output.

Onboard 4GB DDR3 memory and 32GB storage.

The display interfaces are: 1*HDMI, 1*eDP/LVDS, supporting dual-screen display, which can meet the needs of flexible and diverse point-screen applications.

The board has a 3.5mm headset socket and a dual-channel 5W power amplifier speaker interface, which can meet the needs of audio applications.

The main board integrates a gigabit network port, and also integrates a WIFI/Bluetooth module to support various network access methods.

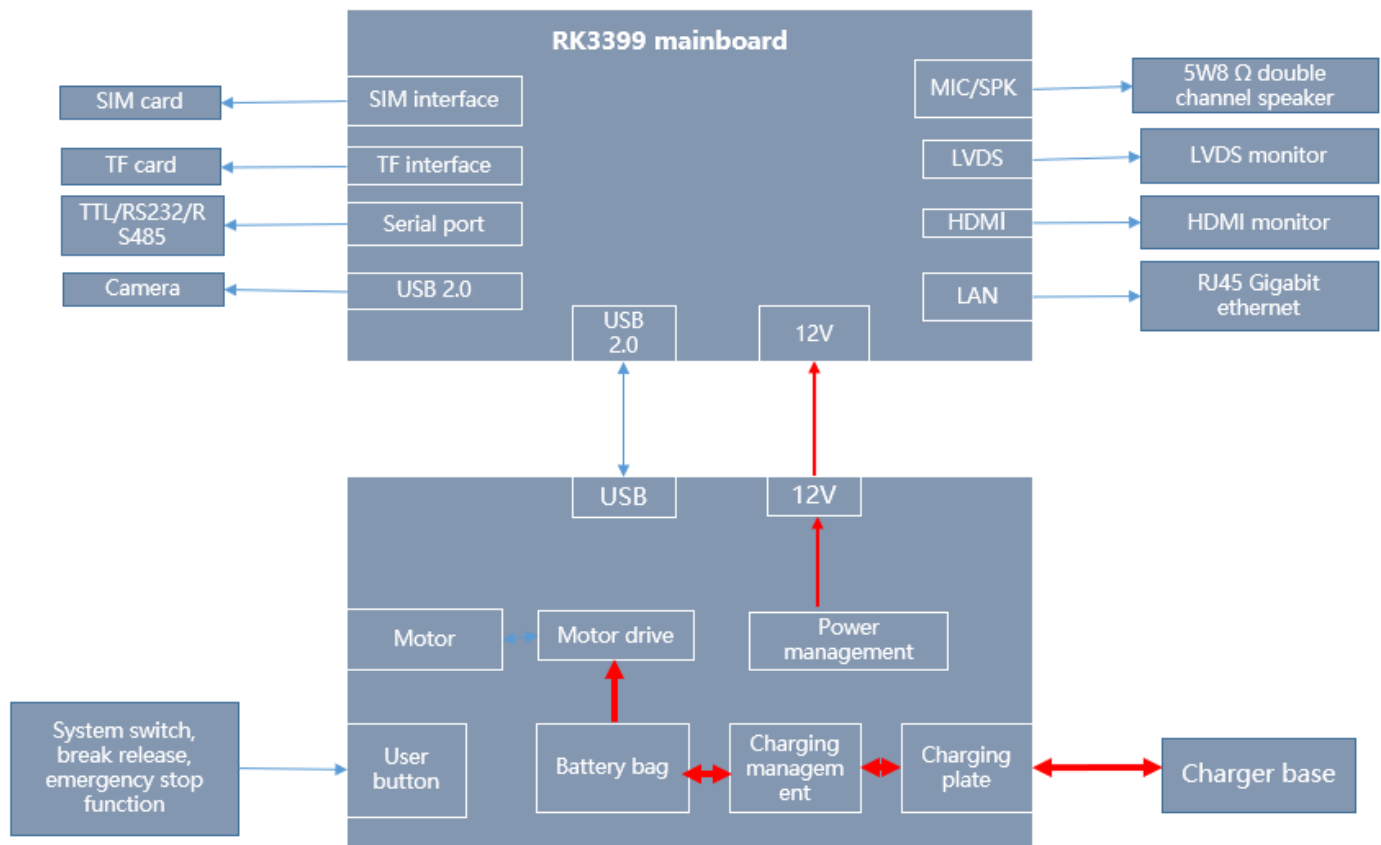
The onboard Mini-PCIe expansion slot supports 4G network card module expansion.

The main board has 5 USB ports and 1 Type-C slot, 2 serial slots, and 1 set of 8 GPIO pins. In addition, the main board has a rich function expansion pin interface.

The main board uses a single 12V DC adapter for power supply.

Characteristics of Main Board:

- ★ Based on Rockchip RK3399 ARM processor solution;
- ★ Display interfaces: LVDS, eDP and HDMI;
- ★ Hardware decoding H.265 high-definition video, support 4K ultra high-definition output;
- ★ Rich functions, onboard 5*USB/2*COM/8*GPIO/1*IR infrared;



6-1 RK3399 Main board basic application diagram

6.3.2 Product specifications

(1) Hardware Specification Sheet

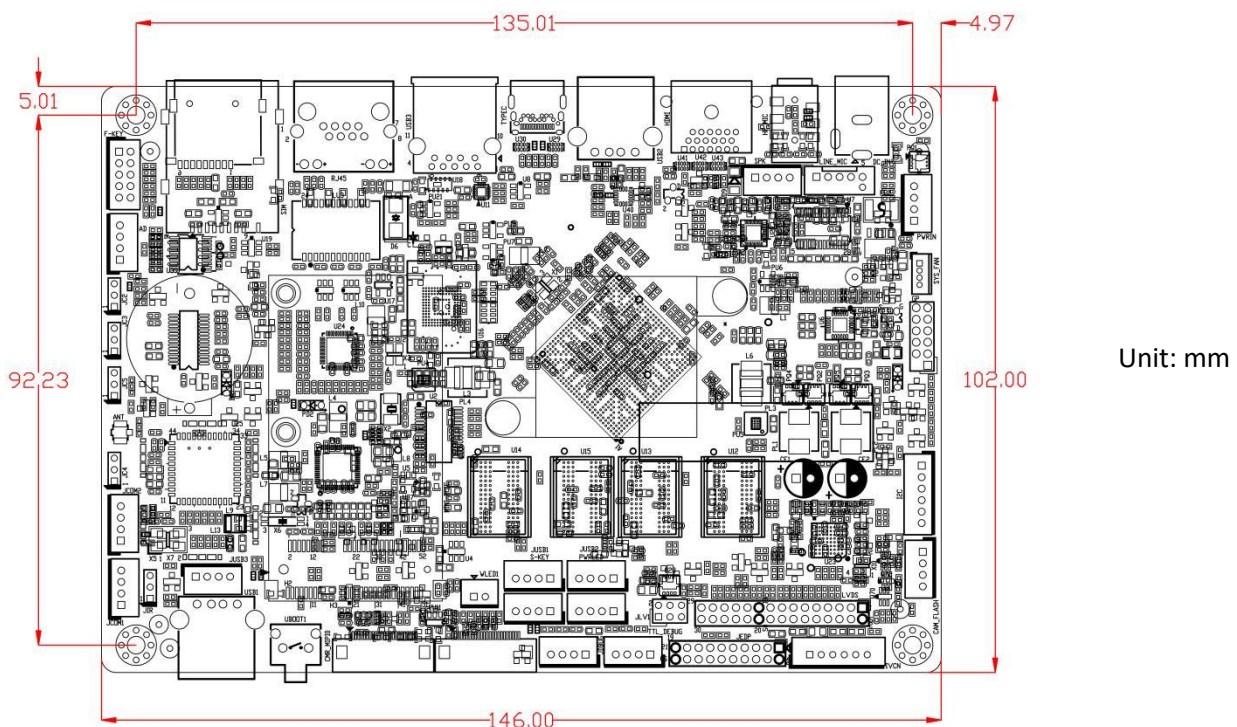
| | |
|-----------|---|
| Processor | Rockchip RK3399 ① |
| RAM | 4GB DDR3 |
| Display | 1*eDP 1*LVDS output resolution maximum supports 4096x2160 ② 1*HDMI output supports 480p/480i/576p/576i/720p/1080p/1080i/4k |
| Internet | 1*RJ45 Gigabit Ethernet 1*WIFI+Bluetooth ③ |
| Audio | 1*3.5mm headset socket 1*LINE_MIC audio pin (with headset socket Co-lay) 1*Dual-channel 5w/8Ω power amplifier speaker pin |
| Storage | 32GB eMMC |
| COM | 2* serial port ④ |
| Others | 4*USB2.0、1*USB3.0、1*USB3.0 Type-C OTG; 1* standard Mini-PCIE slot, for 4G module 1*TF card extension ⑤ 8 GPIO pin 1*IR infrared extension pin 1*I2C touch screen extension pin |

| | |
|---------------------------|--|
| | 2 A/D conversion pin 2*MIPI-CSI2 camera expansion port 1*G-Sensor gravity sensor |
| Power connector | DC2.5*5.5 socket/PH2.0-4pin, 12V DC input |
| Main board specifications | 146*102*22mm, green |
| Operating system | Android 7.1 |
| Working environment | Temperature: 0~+40℃ Humidity: 30~70%RH |

Remark:

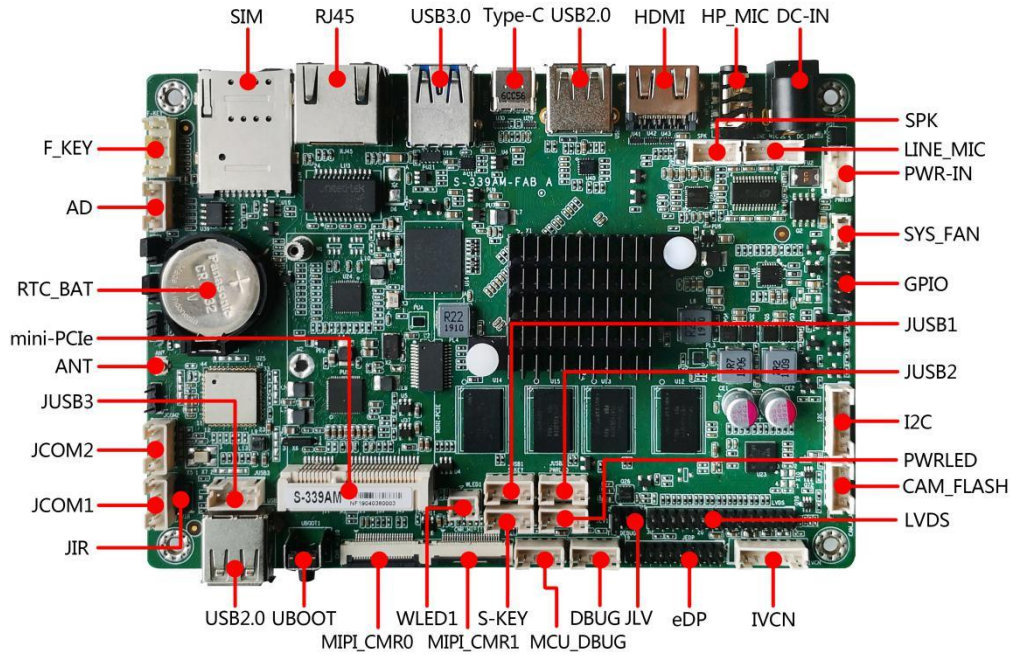
- ①RK3399 is dual-core Cortex-A72 (the highest frequency is 1.8GHz) + 4-core Cortex-A53 (the highest frequency is 1.4GHz);
- ②The eDP interface and the LVDS interface share the backlight and control signals, and cannot be connected to the screen at the same time, only one of the two can be selected;
- ③WIFI specifications: 802.11b/n/g @ 2.4GHz; Bluetooth specifications: Bluetooth 4.0;
- ④COM1 is the Debug interface and supports TTL/RS232, COM2 can communicate with the onboard MCU, and can also be used as an external RS232/RS485 interface;
- ⑤TF card supports maximum expansion to 128GB.

(2) Size of main board



6.3.3 Introduction of Interfaces

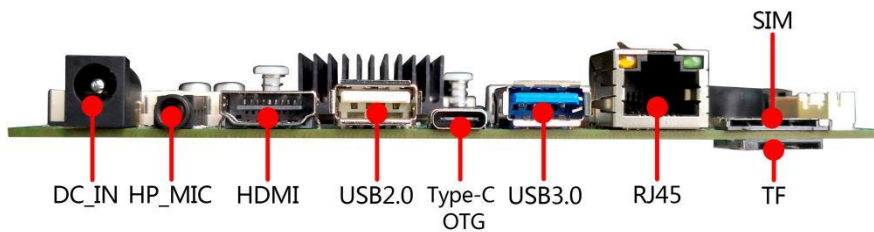
(1) Front view of main board



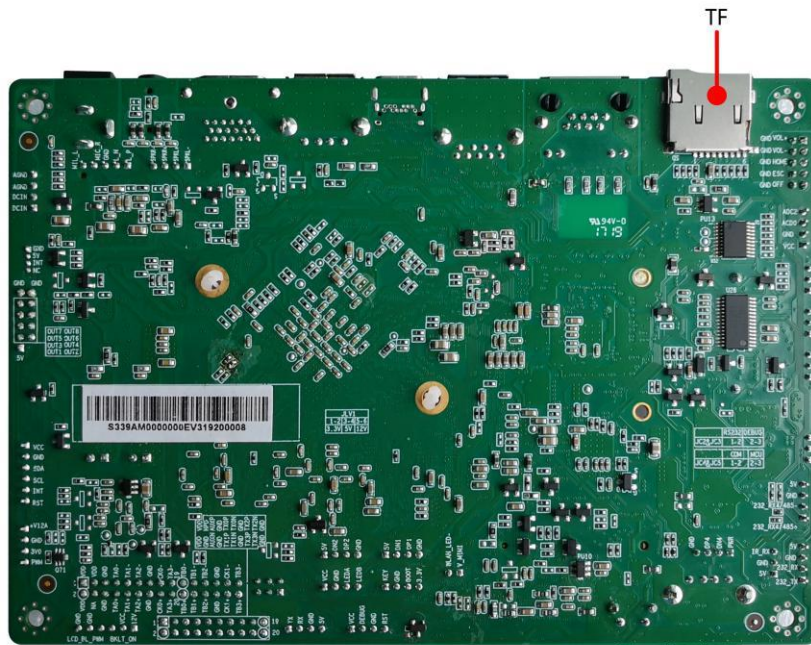
(2) Front IO diagram of the main board



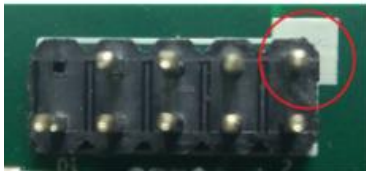
(3) IO diagram behind the main board



(4) Back view of main board

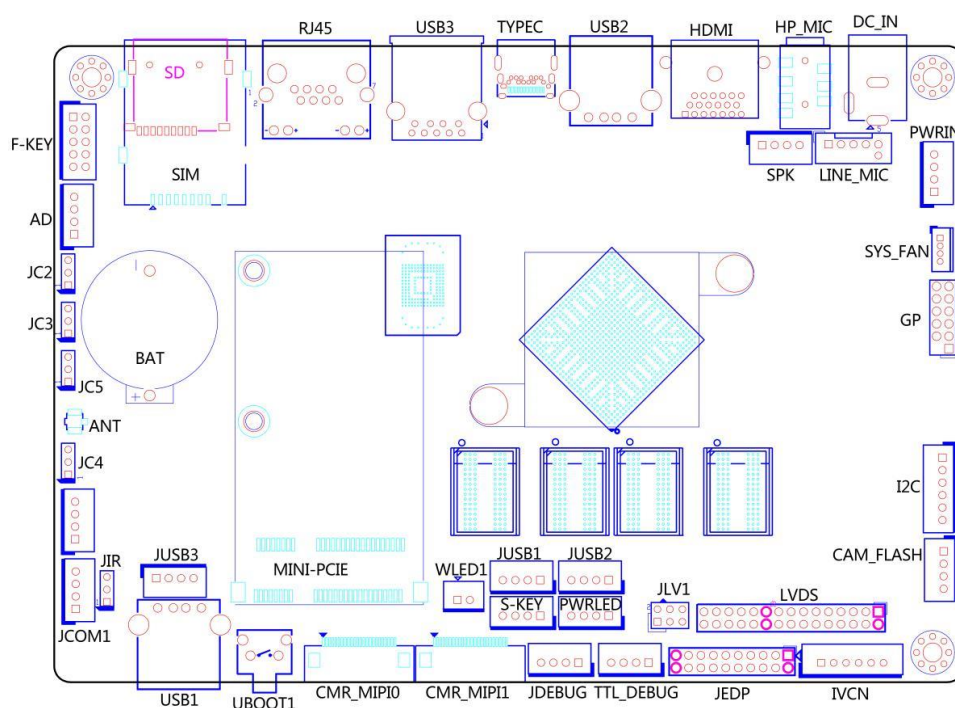


Caution: The identification method of the first pin on the main board is: 1 has a white and bold silkscreen; 2 the pins seen on the back of the main board are square holes.



6.3.4 Definition of pin function

(1) Pin Interface Distribution



(2) Description of silkscreens

| Silkscreen | Description |
|------------|---|
| DC_IN | +12V DC input interface (φ2.5mm base) |
| PWRIN | PH2.0-4PIN power input terminal |
| LINE_MIC | PH2.0-5P LINE-OUT&MIC-IN audio extension socket |
| UBOOT1 | Uboot flash mode button[1] |
| SPK1 | 4-PIN PH2.0 amplifier speaker pin (5W/8Ω) |
| HP_MIC | 3.5mm headset socket |
| HDMI | Standard HDMI HD digital display interface |
| TYPEC | Standard USB3.0 Type-C interface[2] |
| USB1 | Standard USB3.0 Type-A single layer interface |
| USB2 | Standard USB2.0 Type-A single layer interface |
| USB3 | Standard USB3.0 Type-A single layer interface |
| RJ45 | Gigabit RJ45 network interface |
| SIM | SIM card slot |
| SD | TF expanded card slot |
| JCOM1 | PH2.0-4PIN COM1 RS232 mode pin |
| TTL_DEBUG | PH2.0-4PIN COM1 TTL battery mode pin (DEBUG serial port) |
| JCOM2 | 4PIN-PH2.0 RS232/485 serial port 2 sockets |
| DEBUG | PH2.0-4PIN onboard MCU module debugging interface |
| JC2 | COM1 RS232/TTL mode setting jumper [3] |
| JC3 | COM1 RS232/TTL mode setting jumper [3] |
| JC4 | COM2 internal onboard MCU/external JCOM2 setting jumper [4] |
| JC5 | COM2 internal onboard MCU/external JCOM2 setting jumper [4] |
| JIR | DuPont 2.0-3pin infrared receiver extension pin |
| ANT | WIFI/Bluetooth IPEX antenna interface |
| BAT | RTC clock 3.3V battery plug |
| JLV1 | LVDS/eDP screen voltage (3.3/5/+12V) jumper selection |
| CAM_FLASH | Camera flashlight interface |
| F-KEY | Function key pin [5] |
| MINI-PCIE | Mini-PCie module slot |
| CMR_MIPI0 | MIPI-CSI2 camera interface 1 |
| CMR_MIPI1 | MIPI-CSI2 camera interface 2 |
| WLED1 | mini-PCie expansion module signal light |
| JUSB1 | 4PIN-PH2.0 USB2.0 extension pin 1 |
| JUSB2 | 4PIN-PH2.0 USB2.0 extension pin 2 |
| JUSB3 | 4PIN-PH2.0 USB2.0 extension pin 3(and USB1 Co-lay) |
| S-KEY | 4PIN-PH2.0 system power on/off, reset pin |
| PWRLED | Power indicator pin [6] |
| JEDP | eDP HD digital display interface [7] |
| AD | 2 way A/D conversion pin |
| I2C | I2C pin |
| IVCN | LVDS/eDP backlight inverter control interface |
| LVDS | Dual channel 24-bit LVDS interface |
| GP | 10PIN-5.08mm 8 reserved programmable control input and output plug-in terminals |

| | |
|---------|-------------------------------------|
| SYS_FAN | System cooling fan power supply pin |
|---------|-------------------------------------|

Remark:

[1] After the main board is powered on, press and hold the Uboot button to enter Uboot mode to upgrade the system;

[2] Type-C interface only supports Slave mode, connect to computer for firmware upgrade;

[3] JC2 and JC3 jointly determine the COM1 signal connection:

| Mode | RS232 (JCOM3 pin) | TTL (TTL_DEBUG pin) |
|---------|----------------------|---------------------|
| JC2&JC3 | 1-2P short interface | 2-3 short interface |

[4] JC4 and JC5 jointly determine the COM2 signal connection:

| Mode | RS232 (JCOM2 pin) | MCU (485A base) |
|---------|----------------------|---------------------|
| JC4&JC5 | 1-2P short interface | 2-3 short interface |

[5] The extension pin contains function key signals such as volume up, volume down, home, back, and OEM customization;

[6] Preset power indicates two-color lamp extension pin;

[7] The JEDP interface and the LVDS interface share the backlight control pins IVCN and JLV.

(3) Definition of Interface pin and jumper selection

| JP/CN | pin# | Signal | pin# | Signal | Remark |
|----------|------|-----------|------|--------|--------|
| LINE_MIC | 1 | MIC_IN+ | | | |
| | 2 | MIC_IN- | | | |
| | 3 | GND | | | |
| | 4 | LINEOUT_R | | | |
| | 5 | LINEOUT_L | | | |
| JP/CN | pin# | Signal | pin# | Signal | Remark |
| SPK | 1 | SPK_L- | | | |
| | 2 | SPK_L+ | | | |
| | 3 | SPK_R- | | | |
| | 4 | SPK_R+ | | | |
| JP/CN | pin# | Signal | pin# | Signal | Remark |
| PWR_IN | 1 | 12V | | | |
| | 2 | 12V | | | |
| | 3 | GND | | | |
| | 4 | GND | | | |
| JP/CN | pin# | Signal | pin# | Signal | Remark |
| SYS_FAN | 1 | GND | | | |
| | 2 | +5V | | | |
| | 3 | FAN_INT | | | |
| | 4 | NC | | | |
| JP/CN | pin# | Signal | pin# | Signal | Remark |

| | | | | | |
|--------|------|----------|------|--------|--|
| JIR | 1 | +5V | | | |
| | 2 | GND | | | |
| | 3 | IR | | | |
| JP/CN | pin# | Signal | pin# | Signal | Remark |
| S-KEY | 1 | PWR_ON | | | |
| | 2 | GND | | | |
| | 3 | RSET | | | |
| | 4 | GND | | | |
| JP/CN | pin# | Signal | pin# | Signal | Remark |
| F-KEY | 1 | VOL+ | 2 | GND | co-lay 1st PIN and upgrade button co-lay |
| | 3 | VOL- | 4 | GND | |
| | 5 | HOME_KEY | 6 | GND | |
| | 7 | BACK_KEY | 8 | GND | |
| | 9 | OEM_KEY | 10 | GND | |
| JP/CN | pin# | Signal | pin# | Signal | Remark |
| PWRLED | 1 | +3.3V | | | |
| | 2 | GND | | | |
| | 3 | LED_A | | | |
| | 4 | LED_B | | | |

Main board and jumper definition (continued 1)

| JP/CN | pin# | Signal | pin# | Signal | Remark |
|-------|------|---------------|------|--------|--------|
| JCOM1 | 1 | RS232_TX | | | |
| | 2 | RS232_RX | | | |
| | 3 | GND | | | |
| | 4 | +5V | | | |
| JP/CN | pin# | Signal | pin# | Signal | Remark |
| JCOM2 | 1 | RS232_TX/485+ | | | |
| | 2 | RS232_RX/485- | | | |
| | 3 | GND | | | |
| | 4 | +5V | | | |
| JP/CN | pin# | Signal | pin# | Signal | Remark |
| GP | 1 | 5V (NC) | 2 | | |
| | 3 | GPIO1 | 4 | GPIO2 | |
| | 5 | GPIO3 | 6 | GPIO4 | |
| | 7 | GPIO5 | 8 | GPIO6 | |
| | 9 | GPIO7 | 10 | GPIO8 | |
| | 11 | GND | 12 | GND | |
| JP/CN | pin# | Signal | pin# | Signal | Remark |
| I2C | 1 | +3.3V | | | |
| | 2 | GND | | | |
| | 3 | TP_SDA | | | |
| | 4 | TP_SCL | | | |
| | 5 | TP_INT | | | |
| | 6 | TP_RSET | | | |
| JP/CN | pin# | Signal | pin# | Signal | Remark |

| | | | | | |
|-------------------------|---|-----|--|--|--|
| JUSB1 JUSB2 JUSB3 | 1 | +5V | | | |
| | 2 | DT- | | | |
| | 3 | DT+ | | | |
| | 4 | GND | | | |

Main board and jumper definition (continued 2)

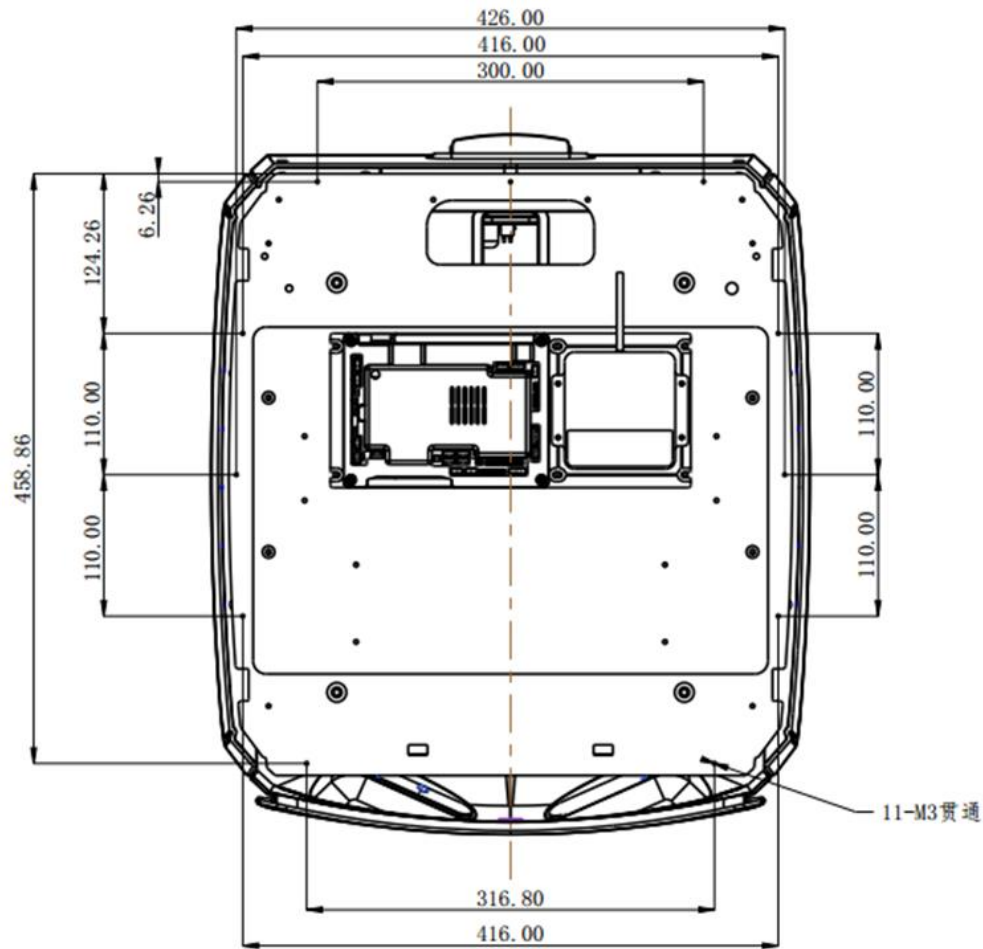
| JP/CN | pin# | Signal | pin# | Signal | Remark |
|-------|------|----------|------|----------|--|
| IVCN | 1 | +12V | | | |
| | 2 | +12V | | | |
| | 3 | BKLT_ON | | | |
| | 4 | BKLT_PWM | | | |
| | 5 | GND | | | |
| | 6 | GND | | | |
| JP/CN | pin# | Signal | pin# | Signal | Remark |
| LVDS | 1 | VCC | 2 | VCC | |
| | 3 | VCC | 4 | | |
| | 5 | GND | 6 | GND | |
| | 7 | TXA0- | 8 | TXA0+ | |
| | 9 | TXA1- | 10 | TXA1+ | |
| | 11 | TXA2- | 12 | TXA2+ | |
| | 13 | GND | 14 | GND | |
| | 15 | TXA_CLK- | 16 | TXA_CLK+ | |
| | 17 | TXA3- | 18 | TXA3+ | |
| | 19 | TXB0- | 20 | TXB0+ | |
| | 21 | TXB1- | 22 | TXB1+ | |
| | 23 | TXB2- | 24 | TXB2+ | |
| | 25 | GND | 26 | GND | |
| | 27 | TXB_CLK- | 28 | TXB_CLK+ | |
| | 29 | TXB3- | 30 | TXB3+ | |
| JP/CN | pin# | Signal | pin# | Signal | Remark |
| JLV1 | 1 | +3.3V | 2 | LVDS_PV | 1-2: choose+3.3V; 3-4: choose+5V; 5-6: choose+12V; |
| | 3 | +5V | 4 | LVDS_PV | |
| | 5 | +12V | 6 | LVDS_PV | |
| JP/CN | pin# | Signal | pin# | Signal | Remark |
| JEDP | 1 | VCC | 2 | VCC | |
| | 3 | HPD | 4 | GND | |
| | 5 | EDP_AUX+ | 6 | EDP_AUX- | |
| | 7 | GND | 8 | GND | |
| | 9 | EDP_TX0+ | 10 | EDP_TX1+ | |
| | 11 | EDP_TX0- | 12 | EDP_TX1- | |
| | 13 | GND | 14 | GND | |
| | 15 | EDP_TX2+ | 16 | EDP_TX3+ | |
| | 17 | EDP_TX2- | 18 | EDP_TX3- | |
| | 19 | GND | 20 | GND | |

Main board and jumper definition (continued 3)

| JP/CN | pin# | Signal | pin# | Signal | Remark |
|------------------------|------|--------------|------|--------|--------|
| AD | 1 | +3.3V | | | |
| | 2 | GND | | | |
| | 3 | AD1 | | | |
| | 4 | AD2 | | | |
| JP/CN | pin# | Signal | pin# | Signal | Remark |
| WLED | 1 | +3.3V | | | |
| | 2 | WLAN_LED- | | | |
| JP/CN | pin# | Signal | pin# | Signal | Remark |
| CAM_FLASH | 1 | +12V | | | |
| | 2 | GND | | | |
| | 3 | Flash_ON | | | |
| | 4 | FLASH_PWM | | | |
| JP/CN | pin# | Signal | pin# | Signal | Remark |
| CMR_MIPI0 CMR_MIPI1 | 1 | AGND | | | |
| | 2 | +2.8V | | | |
| | 3 | +1.8V | | | |
| | 4 | +1.5V | | | |
| | 5 | GND | | | |
| | 6 | CMR_CLK | | | |
| | 7 | GND | | | |
| | 8 | MIPI_RX_CLK+ | | | |
| | 9 | MIPI_RX_CLK- | | | |
| | 10 | GND | | | |
| | 11 | MIPI_RX_D2+ | | | |
| | 12 | MIPI_RX_D2- | | | |
| | 13 | +2.8V | | | |
| | 14 | MIPI_RST0 | | | |
| | 15 | CIF_PDN1 | | | |
| | 16 | I2C_SDA_CAM | | | |
| | 17 | I2C_SCL_CAM | | | |
| | 18 | GND | | | |
| | 19 | MIPI_RX_D3+ | | | |
| | 20 | MIPI_RX_D3- | | | |
| | 21 | MIPI_RX_D0+ | | | |
| | 22 | MIPI_RX_D0- | | | |
| | 23 | MIPI_RX_1+ | | | |
| | 24 | MIPI_RX_D1- | | | |

7. Reference of Structure Design

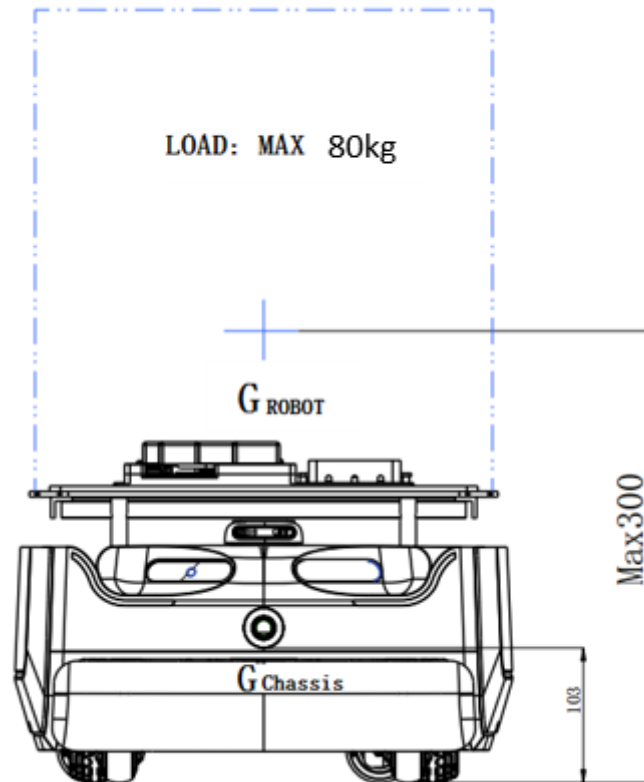
7.1 Installing Interface of Host Computer



As shown in the figure above, there are a total of 11 M3 threaded holes for the installation and fixation of the host computer.

It is recommended to use M3 screws with spring washer and blue anti-loosening glue.

7.2 Instruction of Load Limit

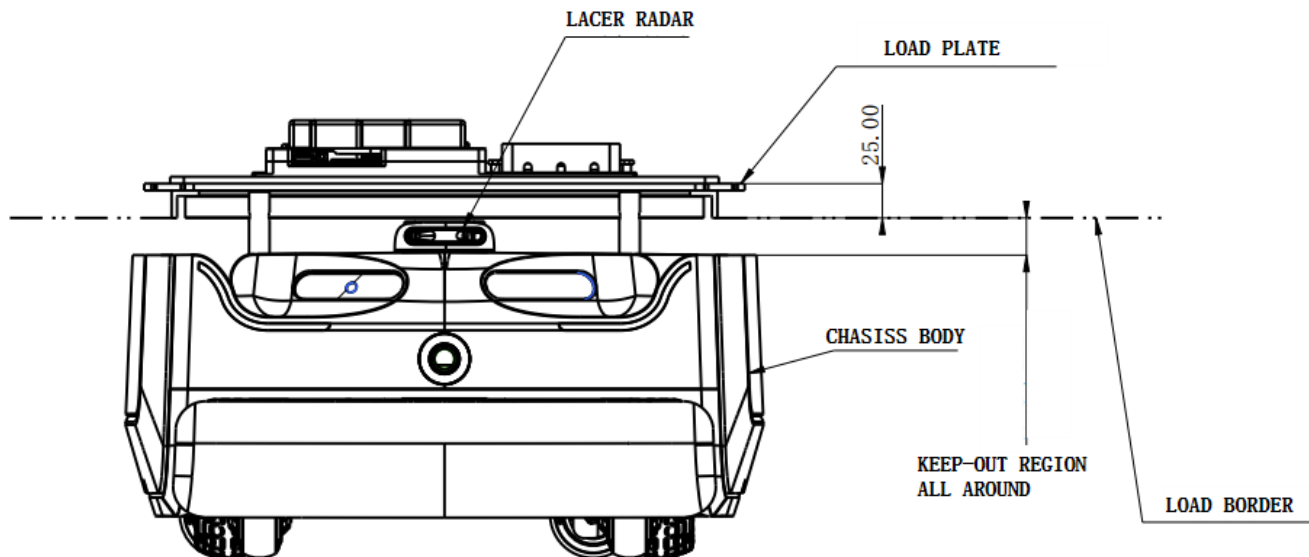


(1) Maximum load of host computer is 80 kg , Rated load is about 50kg.

(2) * It is recommended that the center of gravity of the whole machine is not higher than 300mm from the ground during installation.

- i. *The center of gravity of chassis is the one which Slamtec provides, the height is 103 mm;
- ii. The center of gravity of the whole machine is the overall center of gravity of the chassis plus the robot;
- iii. If the center of gravity of the whole machine exceeds 300mm, the slope-climbing and obstacle-crossing performance may be reduced.

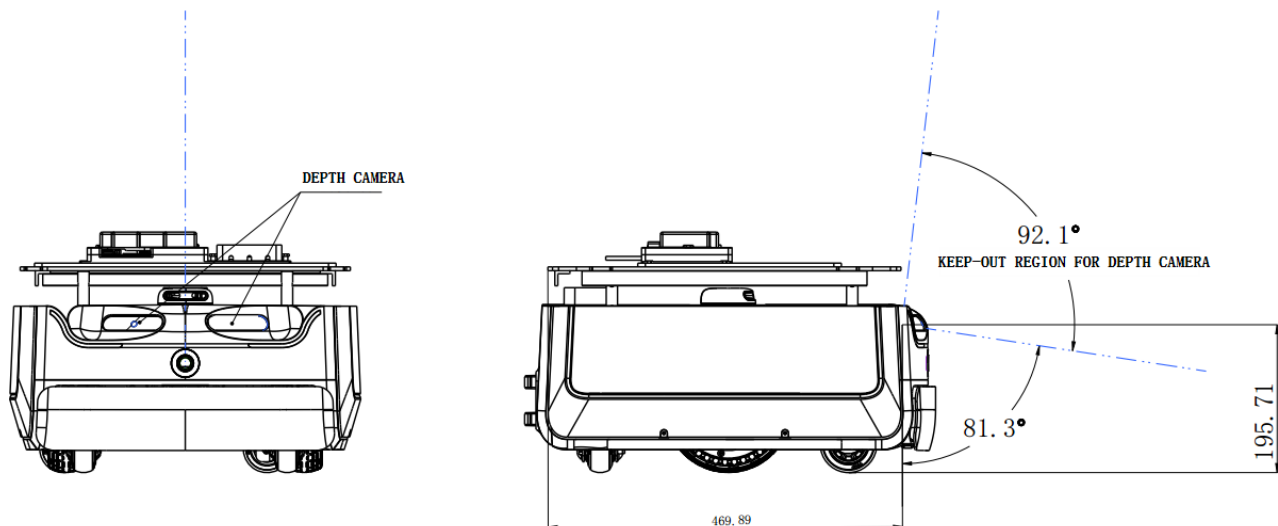
7.3 Radar Clearance Area



There is a radar between the chassis body and the host computer, which requires a certain clearance area to avoid being shielded or interfered;

The boundary of the host computer cannot exceed the lower boundary line of the host computer as shown in the figure.

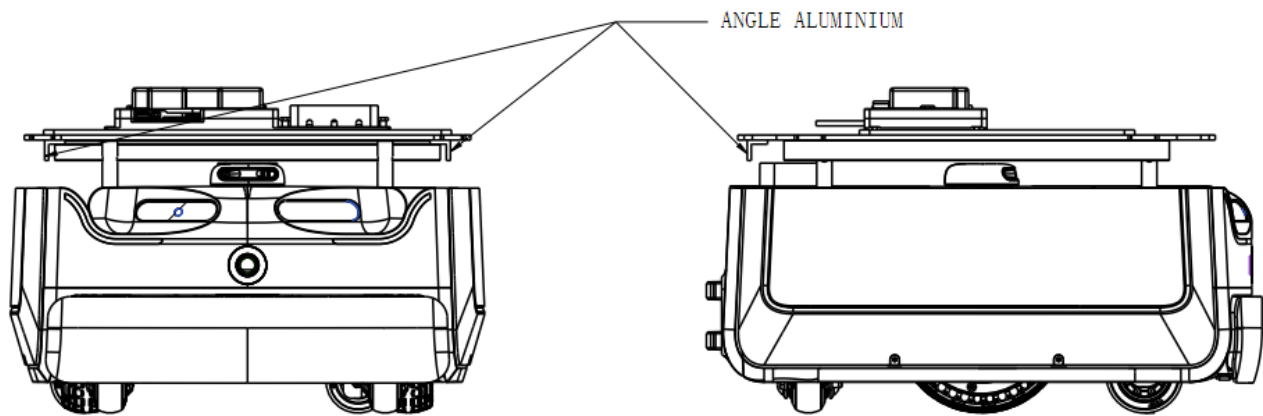
7.4 Deep Camera Clearance Area



There is a deep camera on the chassis, which requires a certain clearance area to avoid being shielded or interfered;

The host computer cannot exceed the clearance area as shown in the figure. Due to the angled layout of the dual cameras, the superimposed clearance area is larger than a single FOV.

7.5 Instruction of Transport Design



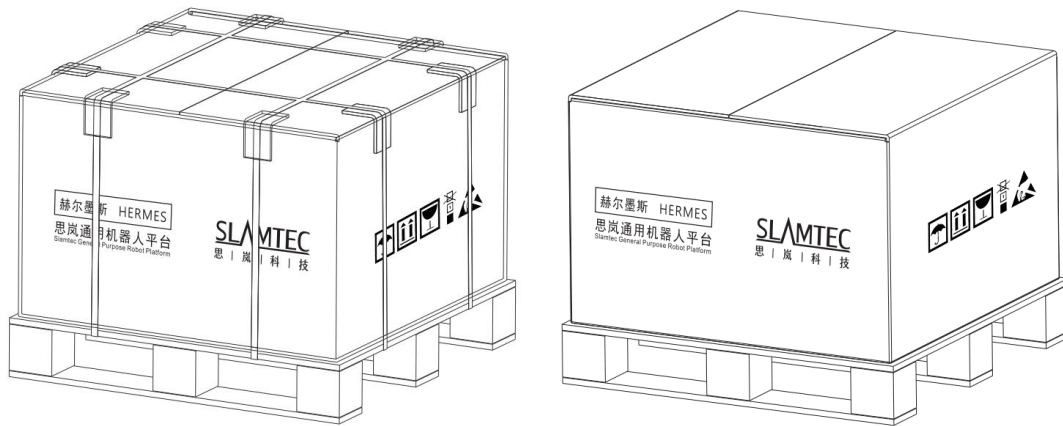
(1) There are three angle aluminums on the left, right and back under the installation board of the host computer, which are used for strengthening support and transporting.

(2) It is recommended to reserve a hand-holding space in the host computer to facilitate transporting.

8. Setup Instructions

8.1 Opening

1. After receiving the Hermes machine, please check whether the packing box is intact as shown in the left picture, and whether the box on the right side of the Hermes sample of the outer box is checked. After confirming that the packing is complete and the box contains Hermes, use packing pliers to cut the packing tape, remove all packing straps and paper corners, it should be shown as on the right picture.



8-1 Hermes unpacking

8.2 Placing Charging Base

Hermes can be charged by returning to the charging base automatically, so the position of the charging base will affect the automatic return charging function of Hermes. When Hermes returns to the charging station, it will generate propelling force. Therefore, it is best to place the charging stand with its back against the wall. The wall must meet the following conditions:

- a. The charging base must be attached to the wall, without no obstacle in the middle, try to avoid the wall with skirting, etc.
- b. The wall material cannot be high-permeability materials, such as mirror or glass
- c. The wall width needs to be at least three times wider than the width of the charging stand
- d. The wall must be a straight wall, not a curved wall

The charging base needs to be connected to a 220V power supply. The length of the external power cord of the charging base is 1.5m. Therefore, it is necessary to ensure that there is a 220 V interface within 1.5m of the wall against which the charging base rests. The ground wiring harness is messy causing unnecessary trouble).

The ground in front of the charging base must meet the following conditions:

- a. Open, with no obstacles within a radius of 2m in front of the charging stand as the center of the circle
- b. Plane, no slope
- c. The ground cannot be covered with soft carpet that causes Hermes to sink more than 2cm

To ensure that Hermes automatically returns to the charging function, it is necessary to ensure that Hermes always starts from the charging base.

Note: If you want to change the position of the charging stand, you need to set the corresponding setting according to the position you need when loading the map. For detailed operations, please see the SDK corresponding interface operation document.

8.3 Power ON/OFF

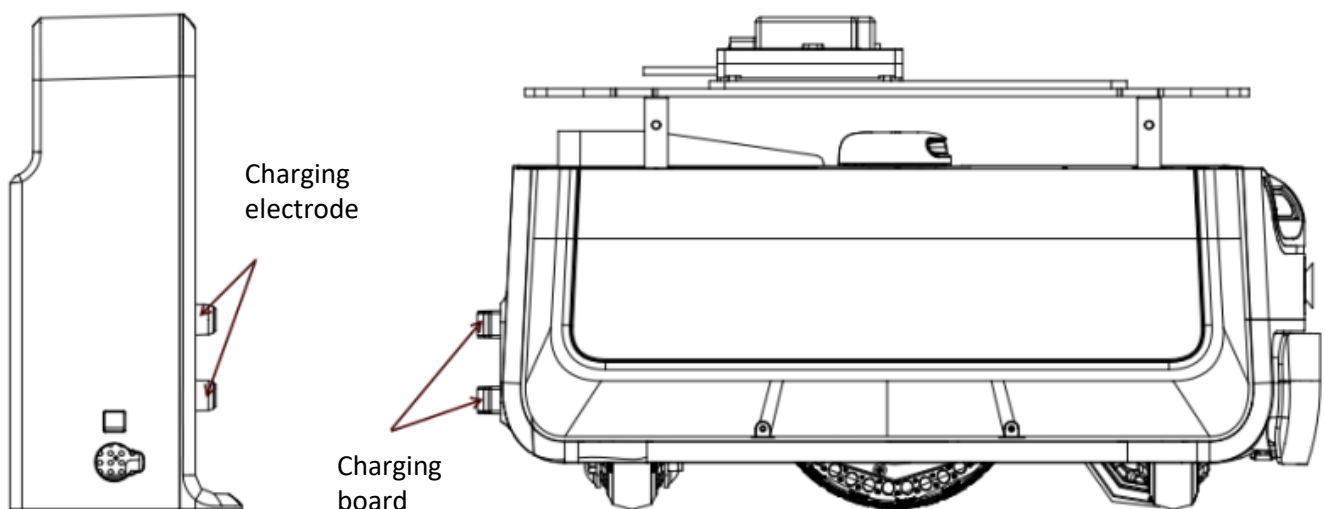
Power on: if the machine is not in the position of charging pile, long press the power switch until the power switch indicator lights up and release it. The machine system enters the startup process, the front light strip lights up, and the wheel hub is in the brake state, indicating that the startup is completed.

If the machine is in the position of charging pile, short press the power switch until the power switch indicator lights up and then release it. The machine system enters the startup process, the front light strip lights up, and the wheel hub is in the brake state, indicating that the startup is completed.

Power off: long press the power switch until indicator light goes out, then release it, the machine enters the shutdown process, the light strip on the front of the machine goes out, and the machine can be pushed arbitrarily, indicating that the shutdown is completed.

8.4 Charging

As shown in the figure below, align the charging piece of the machine with the charging electrode of the charging pile. After waiting for 10 seconds, the front light strip of the robot lights up, the wheel hub enters the braking state, and the breathing light of the charging pile flashes, indicating that charging has started.



8-2 Hermes charging

8.5 Emergency stop & brake and reset

- (1) Emergency stop button

Press the emergency stop button, the Hermes machine will stop immediately, stop and no longer respond to any motion control commands, and the manual push is blocked.

Release the "emergency stop button " and the machine can return to normal working conditions.

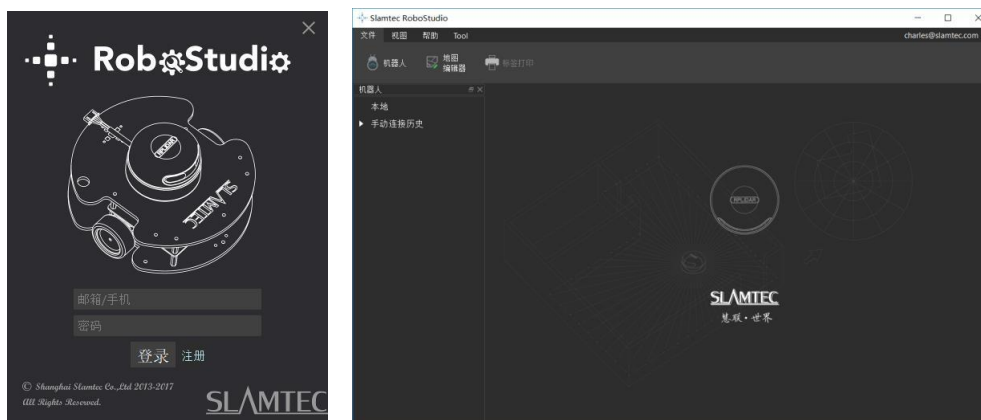
(2) Brake button

Press the "brake button", the Hermes machine will stop immediately, stop and no longer respond to any motion control commands. The machine can be pushed manually, such as pushing it to the charging pile.

Release the "brake button", the machine can return to normal working condition, and the manual push is blocked.

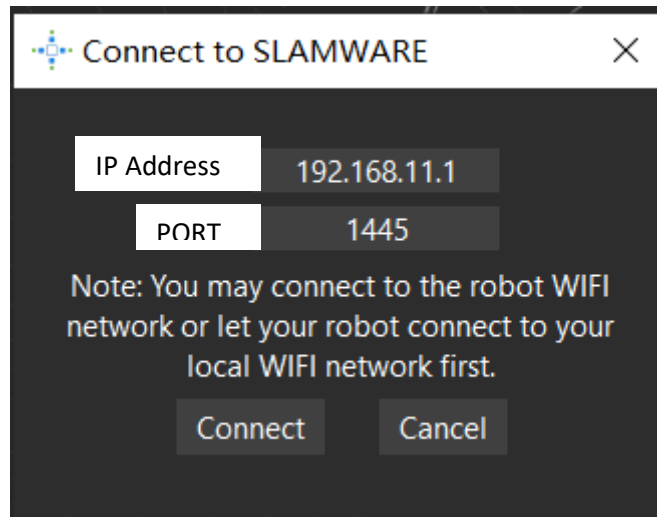
8.6 Map Building and Upload

Download and install the robot graphical control management tool Robot Studio from our official website <http://www.slamtec.com/cn/RoboStudio> to adjust and use Hermes, sign up account and log in. In the menu-toolbar area, click "File-Robot" in turn, and a docking page named Robot will appear on the left side of the workspace, as shown in the figure below. The user connects/disconnects the robot through this page.



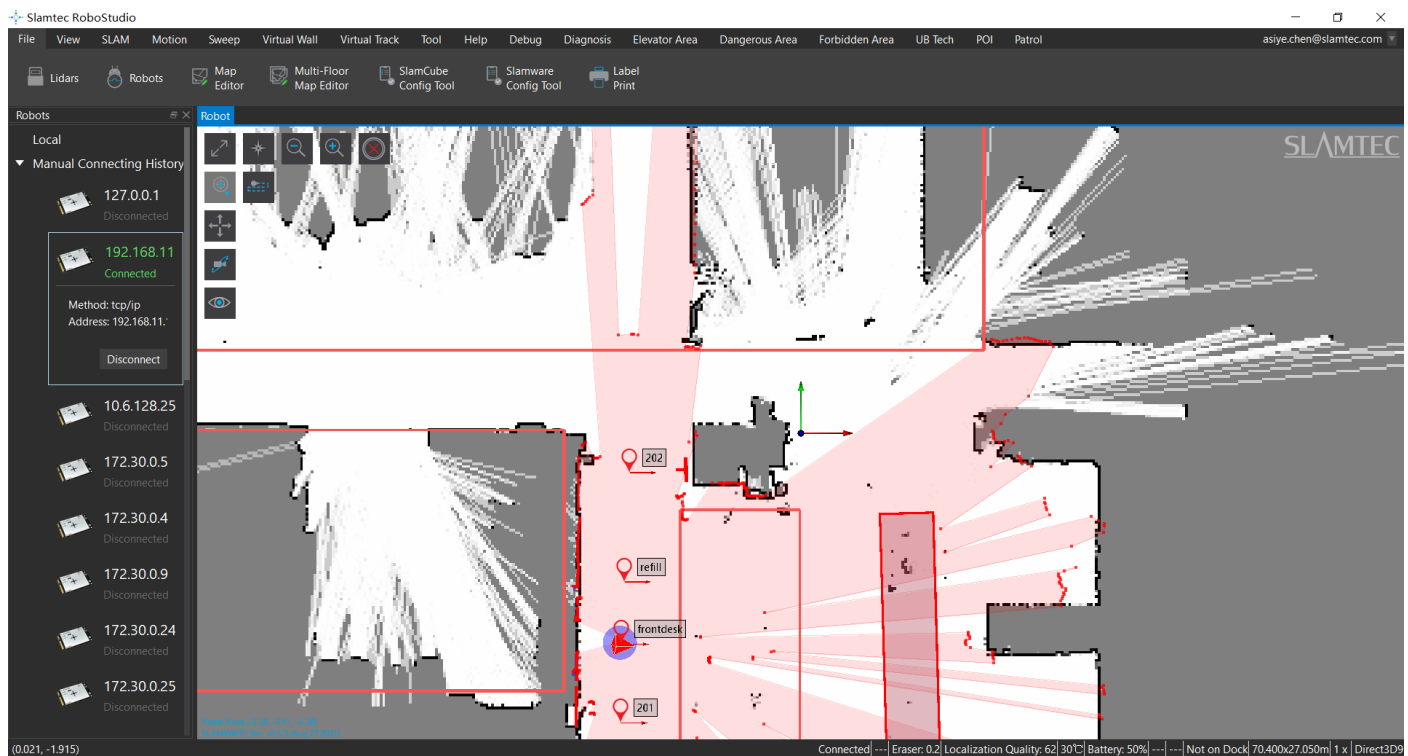
8-3 Rob Studio Robot page

Right-click the blank space of the robot list, click "Manually connect robots" in the pop-up menu, and the connect robot dialog box will pop up (as shown below). Enter the IP address and port number of the Hermes robot above and click the connect button to connect (This connection method is suitable for machines that have been assigned an IP address through the Web portal management backstage). When the computer has been connected to the SSID of the aforementioned Hermes robot through a network adapter (SSID can be viewed on the label of the machine), enter the IP address 192.168.11.1 by default (note that your wireless network adapter IP address should be set to automatically obtain it using DHCP).



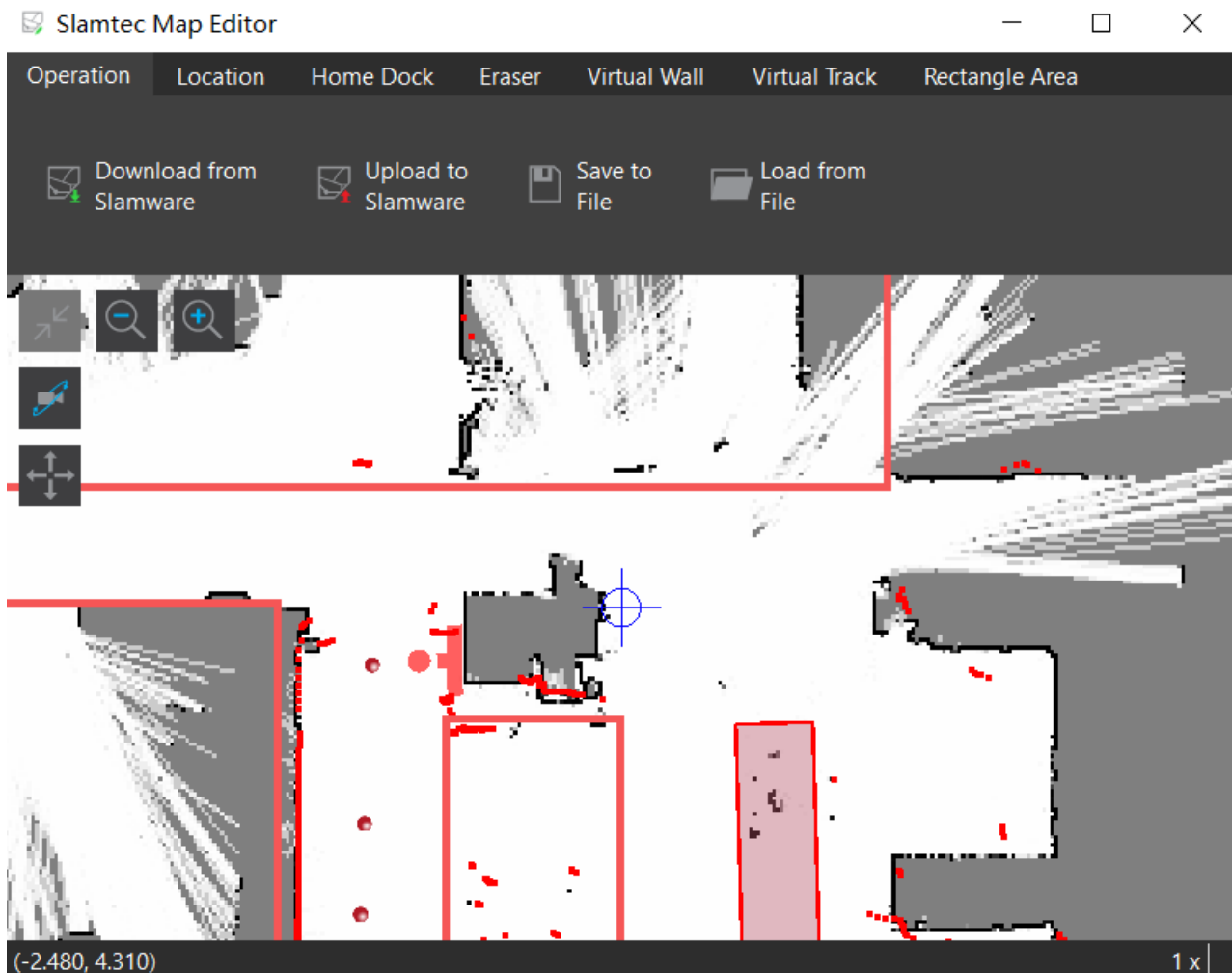
8-4 Rob Studio Robot connecting page

When finishing connecting, the work area will display the robot, map information, and status information. In the robot page, you will find that the name of the connected device turns green, and the status is "Connected", as shown in the figure below.



8-5 Rob Studio Robot connecting page

Left click the spot inside the map-building area, let Hermes build the map. When finishing, please use the virtual wall function to isolate the places that need to be isolated. Then click "File-Map Editor" in turn, choose to save the file or upload to the firmware to save the map.



8-6 Rob Studio Robot map-editing page

There is a difference between the functions of restricted areas and virtual walls.

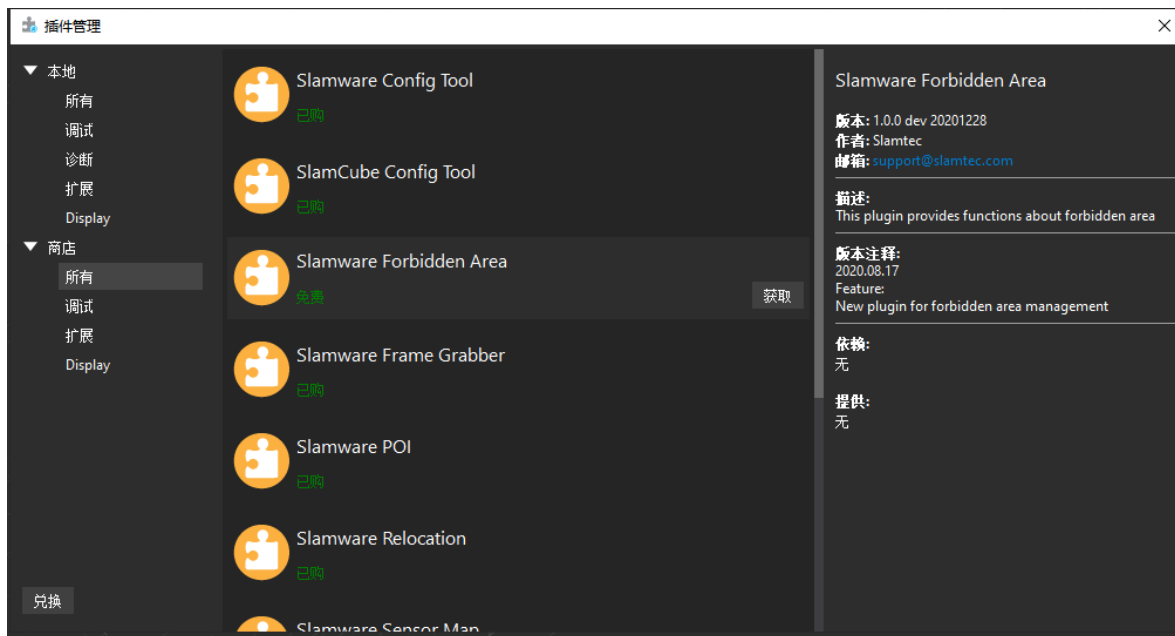
Restricted Area: When the Athena 2.0 is accidentally pushed into the restricted area, the Athena 2.0 machine can be automatically freed from the restricted area by giving a random point in RoboStudio.

Virtual Wall: When a human accidentally pushes Athena 2.0 into the virtual wall, the Athena 2.0 machine cannot automatically get out of the virtual wall and needs to be pushed out by a human at a random point in RoboStudio.

The Forbidden Area management function relies on the Slamware Forbidden Area plug-in. Slamware Forbidden Area is a public plug-in, the computer is connected to the Internet, after logging in RoboStudio, click Tools -> Plug-ins -> Shop -> All -> Slamware Forbidden Area -> Get -> Download -> Restart RoboStudio.

Public plug-in links:

<https://wiki.slamtec.com/pages/viewpage.action?pageId=56164379>)



8-7 RoboStudio Public plug-in

After the plug-in runs normally, connect to the machine, you can see the "Ban zone" toolbar in the menu bar.



8-8 RoboStudio No-go areas

8.7 Host Computer Completes Startup and Loading The Map

Below is a reference example of how to use the SDK to complete the startup and loading of a specific map on the host computer.

```

1.  /*
2.  * upload map file
   to Hermes 3. */
3.  /*
4.  #include <iostream>
5.  #include <rpos\robot_platforms\slamware_core_platform.h>
6.  #include <rpos\robot_platforms\objects\composite_map_reader.h>
7.  #include <rpos\core\pose.h>
8.
9.  using namespace std;
10.
11. int main()
12. {
13.     try
14.     {
15.         string map_path = ".\\map.stcm"; //the path of map
16.         string Hermes_ip = "192.168.11.1"; //the ip of Hermes
17.         int Hermes_port = 1445; //the port of Hermes .default is 1445
18.
19.         rpos::robot_platforms::SlamwareCorePlatform Hermes =
20.             rpos::robot_platforms::SlamwareCorePlatform::connect(Hermes_ip, Hermes_port);

```

```

21.    //connect to the Hermes
22.    rpos::robot_platforms::objects::CompositeMapReader cmapreader;
23.    //map reader
24.    rpos::core::Pose Hermes_pose = rpos::core::Pose(rpos::core::Location(0, 0, 0));
25.    //the Hermes pose in map(Hermes_pose should be the Hermes's real pose in new map)
26.    //using Hermes.getpose() to get the old Hermes pose
27.    auto map = cmapreader.loadFile(map_path);
28.    //load map
29.    Hermes.setCompositeMap(*map, Hermes_pose);
30.    //set compositemap
31.    rpos::core::Pose home_pose = rpos::core::Pose(rpos::core::Location(0, 0, 0));
32.    //the home pose in map(home_pose should be the home's real pose in new map)
33.    //using Hermes.gethomepose() to get the old home pose
34.    Hermes.setHomePose(home_pose);
35.    //set home pose
36.    }
37.    catch (rpos::robot_platforms::ConnectionFailException &e)
38.    {
39.        cout << "connect failed on " << e.what() << endl;
40.    }
41.    catch (rpos::system::detail::ExceptionBase &e)
42.    {
43.        cout << "failed on " << e.what() << endl;
44.    }
45.
46.    return 0;
47. }

```

Further motion deployment details, please see the SDK instruction document

9. Connection to Computer

【Step 1】 The hotspot of the computer connected to the chassis

HERMES's hotspot is auto-started by default, the hotspot format is: SLAMWARE-XXXXXX

Hot spot identification method: query the last six digits of the SSID in the chassis label.



9-1 Chassis label SSID

For example, if the label SSID: Robot- E2A29E, the hot spot of this Chassis is SLAMWARE- E2A29E

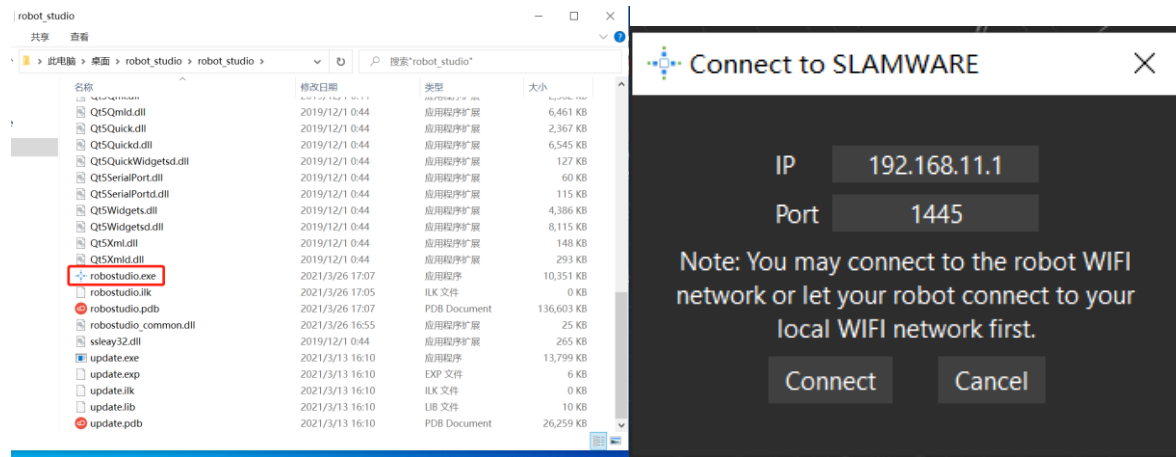
【Step 2】 Download and install Slamtec RoboStudio from the official website of Silan



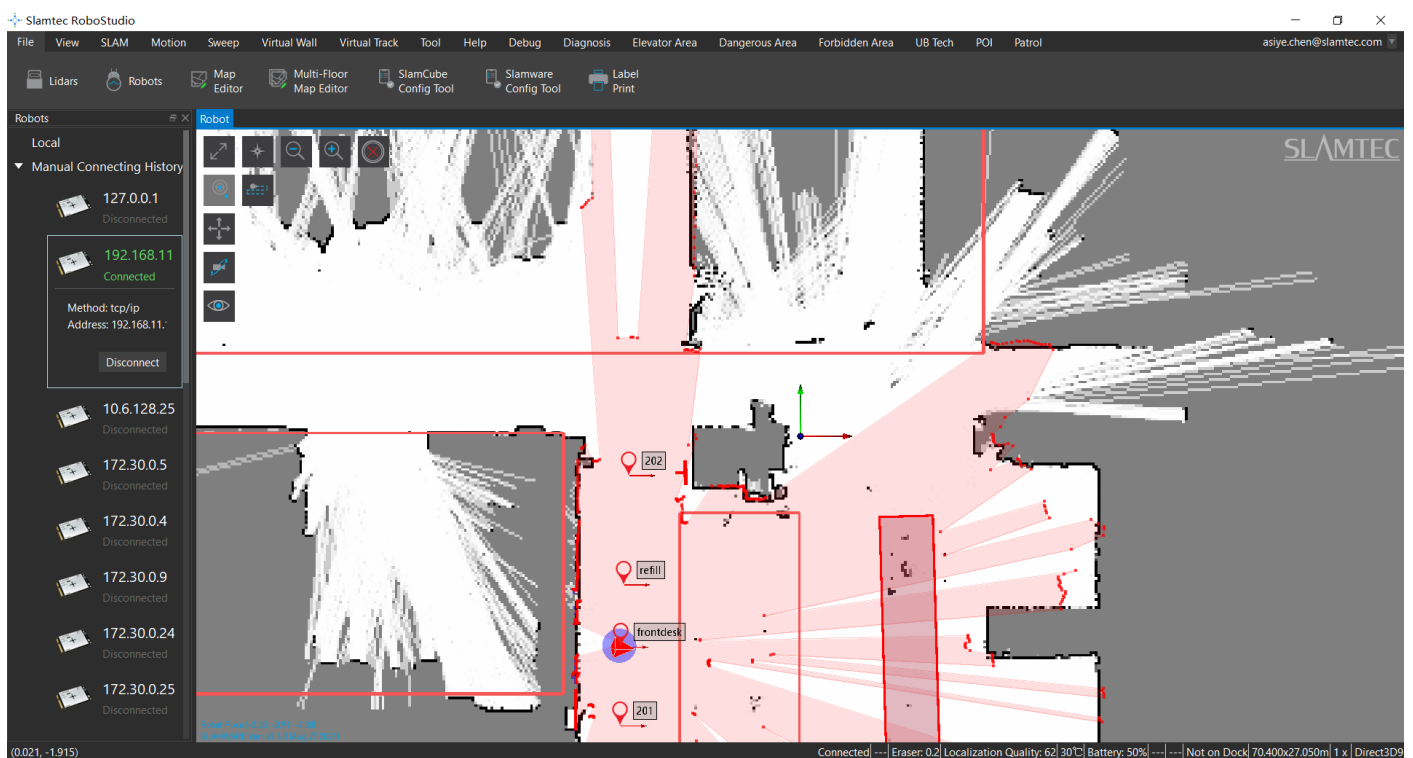
9-2 Official Slamtec RoboStudio

If you downloaded slamtec robostudio, After logging in to RS, click the "Robot" option and manually connect the robot with the right mouse button.

[step 3] if you downloaded slamtec robostudio, run "robostudio.exe", enter the interface of slamtec robostudio, enter the IP address and port, click "connect", and RS login succeeds.



9-3 Robo studio login screen



9-4 Robo studio interface

Note : The method of IP address query is to press the shortcut key, Windows+R, and enter the code ipconfig. Copy the IP of the default gateway and paste it into the IP address box of Slamtec RoboStudio. Click Connect to enter Slamtec RoboStudio.



```
C:\WINDOWS\system32\cmd.exe
C:\Users\ena.liu>ipconfig

Windows IP 配置

无线局域网适配器 本地连接* 1:

    媒体状态 . . . . . : 媒体已断开连接
    连接特定的 DNS 后缀 . . . . . :

无线局域网适配器 本地连接* 2:

    媒体状态 . . . . . : 媒体已断开连接
    连接特定的 DNS 后缀 . . . . . :

无线局域网适配器 WLAN:

    连接特定的 DNS 后缀 . . . . . :
    本地链接 IPv6 地址. . . . . : fe80::78a1:69ee:385e:c308%7
    IPv4 地址 . . . . . : 192.168.11.243
    子网掩码 . . . . . : 255.255.255.0
    默认网关. . . . . : 192.168.11.1

以太网适配器 蓝牙网络连接:

    媒体状态 . . . . . : 媒体已断开连接
    连接特定的 DNS 后缀 . . . . . :

C:\Users\ena.liu>
```

9-5 Method of obtaining an IP address

10. Adjusting Tools

10.1 RoboStudio

RoboStudio graphical tools are used to adjust and use Hermes, please download and install it from our official website: <http://www.slamtec.com/cn/RoboStudio>, and coming with manual to introduce those features.

10.2 Web Management Backstage

In the process of developing, adjusting and using SLAMWARE equipment, various operations can be performed on the equipment through the web management backstage, such as viewing basic information, updating the version, configuring WiFi, etc. (Default username: admin, default password: admin111)

Currently, web management backstage supports following functions:

1. Check basic information of the device
2. Restart the module
3. Update the firmware

Slamtec will regularly provide Hermes firmware updates and upgrades. You can easily upgrade the firmware for Hermes through the management backstage. Please obtain the latest firmware from sales or technical support personnel. The update process will last 5-10 minutes. The buzzer of Hermes will continue to sound during the update, and Hermes will automatically restart after the update. Before that, please make sure that Hermes has sufficient power.

4. Configuring WIFI
5. Start the SLAMWARE Core diagnostic mode
6. Modify the administrator password

More details on usages please refer to:

<https://wiki.slamtec.com/display/SD/SQ001+SLAMWARE+Web+Portal+Function+Overview>

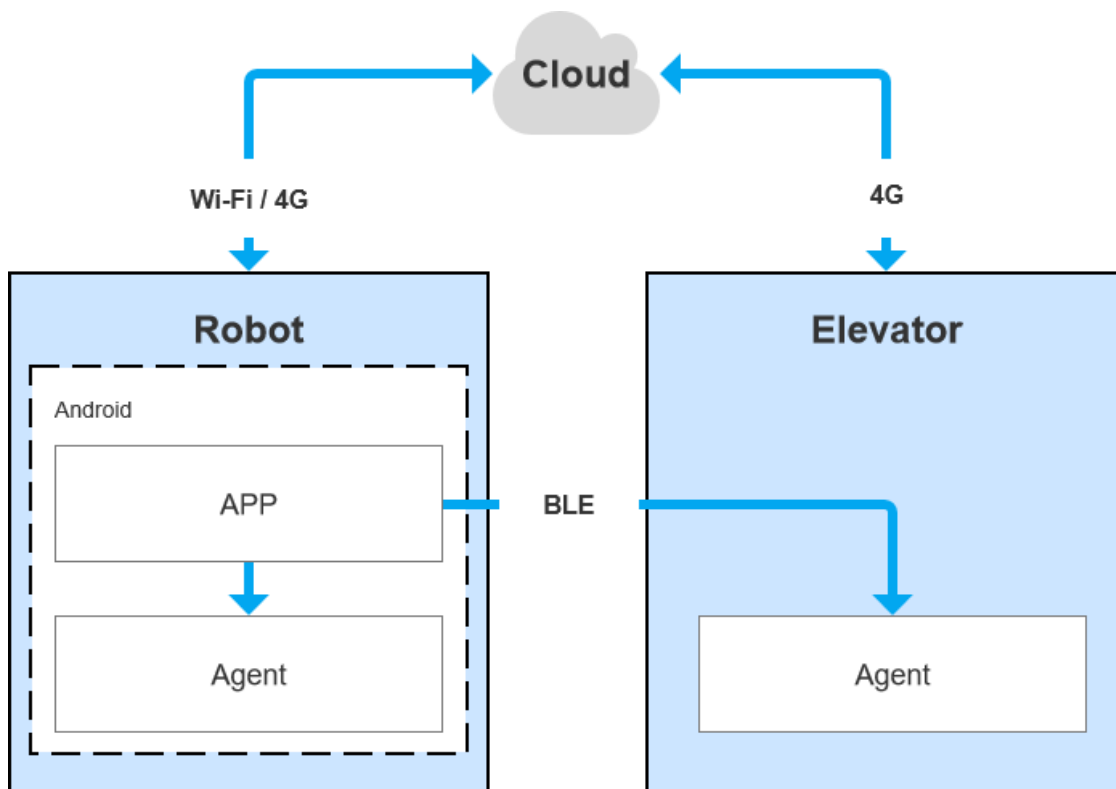
11. Developer Tools

11.1 Start Using

The Agent SDK of the Hermes chassis is developed based on the C++ language to reduce user access costs and improve the robustness of the SDK. At the same time, it has strong compatibility and supports multiple languages such as Java, C++, C, and Kotlin. The following is a detailed introduction to the relevant examples and usage guidelines of the Agent SDK call based on the Hermes chassis.

11.2 Inter-system Adjusting Framework

Robot App controls the robot's positioning, movement, and return to piles through communication; at the same time, Robot App sends instructions to the robot according to various business scenarios, and Robot Agent will provide data interfaces, task operation interfaces, and business services to Robot App.



11-1 COMMUNICATION BETWEEN EACH SYSTEM OF HERMES

11.3 Instructions of Each System

11.3.1 Robot Agent

Robot Agent is a service program running on the Hermes chassis, through which the cloud and the elevator control terminal communicate with the elevator control equipment. Inside the Robot system, the Robot Agent communicates with the Robot App, receives instructions from the Robot App to control the Robot, and sends the Robot status at the same time.

The core function of Robot Agent is:

- ✓ Communicate with the Robot Cloud, Robot APP, send the Robot status and receive instructions

11.3.2 Elevator Agent

Elevator Agent is a service program running on the Linux system of the elevator control main control box. The cloud and the robot end communicate with the elevator control equipment through it. Inside the elevator control system, the Elevator Agent communicates with the Elevator Controller through UDP, sending elevator control instructions and obtaining elevator status.

The core function of Elevator Agent is:

- ✓ Communicate with the Robot Cloud, Robot APP, send the elevator status and receive instructions of elevator control
- ✓ Communicate with the Elevator Controller, receive the elevator status and send instructions of elevator control

11.3.3 Robot Cloud

Robot Cloud is a set of services provided to realize remote management, scheduling, and control of robots. It runs in the cloud and communicates with the robot at one end and the elevator control equipment at the other end. Therefore, elevator control is part of the function. Robot Cloud communicates with the Elevator Agent running on the main control box of the elevator control through the MQTT protocol.

Its core functions include:

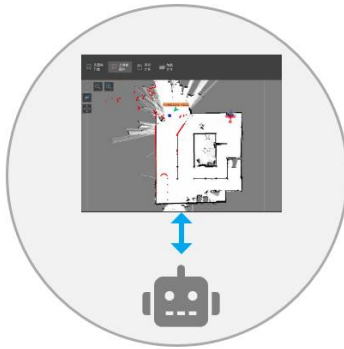
- ✓ Send instructions, control the elevator to the designated floor
- ✓ Send instructions, control the elevator to open the door
- ✓ Send instructions, control the elevator to close the door
- ✓ Receive the up/down status of elevator
- ✓ Receive the current floor of the elevator

11.3.4 Robot App

Open-Source application – Restaurant Delivery App

The restaurant delivery app is a service program running on the robot. The application scene is a restaurant. It draws a map and loads it to the robot's local area through RoboStudio graphical tools. It is a universal application for human-computer interaction to achieve multi-point task delivery.

DEPLOYMENT



1. Personnel sketching map and load to the Robot

DELIVERY PROCESS



2. Restaurant waiter sets menu into the Robot



3. Waiter enters designated table number



4. Robot send items to the destination



5. Robot informing customer "Here's your order!" when reaching destination



6. Robot returning to picking up point and wait for another order

11-2 RESTAURANT DELIVERY BUSINESS FLOWCHART

Its core functions include:

- ✓ Get device battery percentage
- ✓ Get health status info of the device
- ✓ Get POI info
- ✓ Get password of the action
- ✓ Create new action
- ✓ Get current action
- ✓ Stop current action
- ✓ Shut down of restart Robot

11.4 Demonstrations of Code

1. The following is an example of the Robot APP calling the Robot Agent interface to check the battery status

GET <http://127.0.0.1:1448/api/core/system/v1/power/status>

The format of the returned data is application/json

```
interface AgentApi {
    /**
     * get方式调用 value: 接口地址
     * PowerStatus: 接口返回json格式对应的bean格式的data class的值
     */
    @GET("/core/system/v1/power/status")
    fun queryPowerStatus(): Call<PowerStatus>
}

/**
 * batteryPercentage : 90电池电量百分比, 0 ~ 100
 * dockingStatus : 对桩状态
 * isCharging : 是否正在充电...
 */
data class PowerStatus(
    val batteryPercentage: Int, val dockingStatus: String, val isCharging: Boolean,
    val isDCConnected: Boolean, val powerStage: String, val sleepMode: String
)

/**
 * retrofit接口代理类
 */
object AgentServiceCreator {
    fun <T> create(serviceClass: Class<T>, timeout: Long): T =
        Retrofit.Builder().baseUrl("http://127.0.0.1:1448/api/")
            .addConverterFactory(GsonConverterFactory.create()).client(
                OkHttpClient.Builder().retryOnConnectionFailure(true)
                    .connectTimeout(timeout, TimeUnit.SECONDS)
                    .addInterceptor { chain ->
                        val originalRequest = chain.request()
                        val requestBuilder =
                            originalRequest.newBuilder().addHeader("Connection", "close")
                        chain.proceed(requestBuilder.build())
                    }.build()
            ).build().create(serviceClass)
}

// 查询电量, 返回值为powerstatus
val powerStatus = AgentServiceCreator.create(AgentApi::class.java, 1L).queryPowerStatus().await()
    Result.success(powerStatus)
```

2. The following is the Robot App calling the Robot Agent interface to make the robot move across floors

POST <http://127.0.0.1:1448/api/core/motion/v1/actions>

The request message format is application/json

```

{
  "action_name": "slamtec.agent.actions.MultiFloorMoveAction",
  "options": {
    "target": {
      "poi_name": "201" // 表示前往名称为 201 的 poi
    }
  }
}
} // JavaScript Document

```

11.5 Details Of Robot API

| FUNCTION OF MODULES | API LIST |
|--|-------------------------------|
| Locate, map building-related functions | Get the Robot location |
| | Set the Robot location |
| | Get quality of location |
| | Whether support locating |
| | Start/Close locating |
| | Whether start map building |
| | Start/ pause map building |
| | Get location of power station |
| | Set location of power station |
| | Get current map |
| | Delete current map |
| Mark map elements manually | Get all virtual line segment |
| | Add virtual line segment |
| | Adjust virtual line segment |
| | Delete virtual line segment |
| | Delete virtual line segment |
| | Get all POI in current map |
| | Add POI |
| | Empty POI |
| | Find POI according to ID |
| | Modify POI |
| | Delete POI |
| Motion control of the Robot | Get all supported actions |
| | Get current action |
| | Stop current action |
| | Create new action |
| | Check action status |
| Firmware Upgrade | Get firmware upgrade process |
| Android application management | Get all custom installed apps |
| | Install APP |

| | |
|---|--|
| | Uninstall an APP |
| Multi-floor map and POI management, taking elevator, etc. | Move across floors |
| | Go back across floors |
| | Get all floor info |
| | Get floor info of floor of the robot |
| | Setup info of floor of the robot |
| | Get POI info |
| | Upload map to the robot |
| | Long-lasting save the map |
| | Reload the map |
| Delivery service-related interfaces | Get password of the action |
| | Set password of the action |
| | Get configuration info of the device |
| | Get setup info related to the delivery |
| | Check task info |
| | Create task |
| | Cancel all task |
| | Cancel some task |
| | Get current mission status |
| | Stop/ continue current mission |
| | Start picking up items |
| | End picking up items |
| | Get info of objects |
| | NOTE: delivery business please inform marketing department |
| Restaurant delivery service-related interfaces | Get the current battery percentage |
| | Get the health info of the device |
| | Get POI info |
| | Get password of the action |
| | Make up new actions |
| | Get current action |
| | Terminate current action |
| | Shut down or restart the robot |

MORE DETAILS OF API: <https://github.com/slamtec/HermesSampleApp>

12. Introduction And Use Of Elevator Control

12.1 Introduction



12-1 INTELLIGENT ELEVATOR CONTROL DEVELOPED BY SLAMTEC

Intelligent elevator control, independently developed by Shanghai SLAMTEC CO., Ltd, can provide accurate detection of elevator status, program control call elevators, control elevators, combined with Mercury II hotel robots, helping the robots to take and exit the elevators autonomously. Providing reliable solutions to multi-floor operation scenarios. In addition to working with hotel robots, the product can be used as an independent set of solutions. Through the API interface we provide, this product can also interact with other smart devices or products to meet the different customization needs of customers. At the same time, the product can also be seamlessly connected to the Hermes chassis, to provide technical service support for more specific needs in other scenarios.

12.2 Features

12.2.1 Intelligence Elevator Control

The core function of this product is to help robots and other intelligent devices to control the elevator, such as calling the elevator, going to the designated floor, and controlling the elevator to open and close the door. This function greatly improves the business scenario of robots and breaks the previous limitation that robots can only work on the same floor.

12.2.2 Intelligence Status Detection

Through the built-in sensor and adaptive algorithm, this product can accurately detect the current floor, up and down status of the elevator, real-time to the millisecond level, with an accuracy of more than 96%, providing a very critical foundation so that the robot can enter and exit the elevator correctly and complete the work.

12.2.3 Elevator Diversity Adaption

The main control box has developed a variety of optimized filtering algorithms, so that this product is suitable for many different types of elevators, such as single-door elevators, double-door elevators, front and rear door elevators, etc. As it covers as many scenes as possible, this product can be used in most elevators at present. Users only need to simply calibrate and adjust through the APP provided after installing the equipment.

12.2.4 Multi-Level Network Adaption

Considering the limitations of the elevator network, how to ensure data interconnection and program interoperability is a very critical factor, and relatively it is also a difficult point. After continuous optimization iterations, we finally found a way to solve this problem. This product provides 4G, WIFI, BLE and other multi-level network communication methods to interact with robots and other smart devices to ensure the reliability of the communication link.

12.2.5 OTA Remote Upgrade

Support OTA remote upgrade of software and firmware, and batch deployment. At the same time, it provides support for VPN, which can remotely log in to the Linux system of this product for upgrades and other operations. Through the OTA function, real-time updates, upgrades and optimization can be done.

12.2.6 Interface Support

The intelligent elevator control provides a consistent API interface to the outside world, supports Bluetooth, MQTT, and HTTP communication protocols. Customers can control and interact with the elevator by writing their own program code. At the same time, it supports secondary development to meet the different customization needs of customers.

12.2.7 Swipe To Bypass

For some elevators that require a swipe card to ride, this product can also be easily supported. Just install the equipment we specify when installing the device, and then turn on the swipe card to bypass it in the APP. In this way, even if there is a card reader, it can be easily bypassed and freely enter and exit the elevator.

12.2.8 Unified Management

The cloud platform provided by SLAMTEC can perform real-time monitoring of the status of all deployed products, batch upgrades, and further data mining through online management, information statistics, equipment monitoring, etc., to provide exclusive accurate data models for hotels or commercial buildings, to guide them to improve their overall operational capabilities and service quality.

To know more about the detailed solution of elevator control, obtain it from the marketing department.

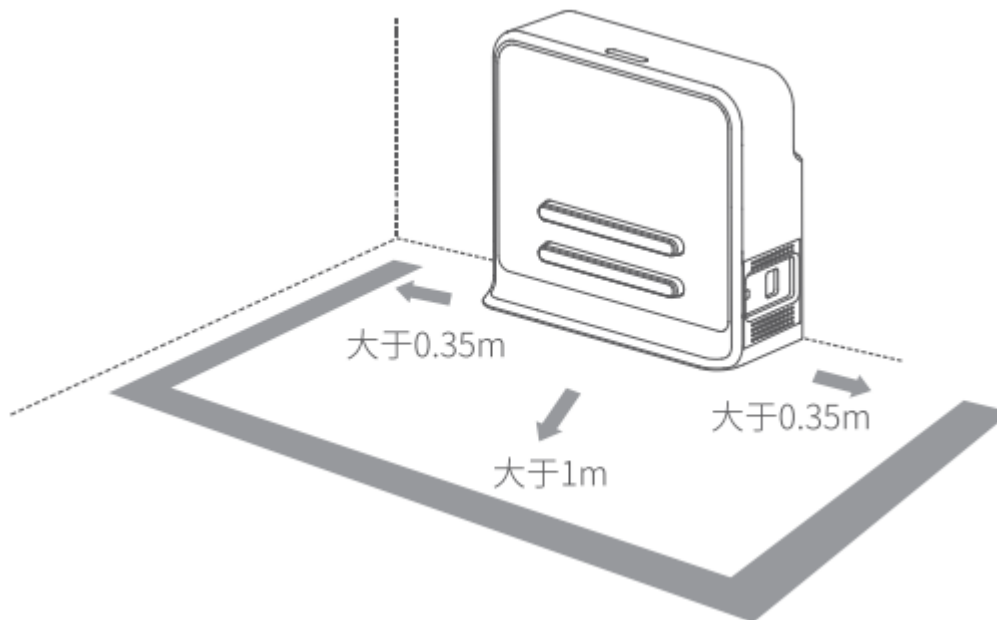
[Elevator control user manual->>](#)

13. Special Note

13.1 Charge point deployment

Precautions for the selection of charging pile location:

- (1) The charging pile should be placed on the wall with a space of more than 0.35 meters on both sides and more than 1 meter in front;
- (2) The charging pile shall be close to the wall, and shall not be placed in the mirror wall, back hollowed out and other areas, etc;
- (3) The position of the charging pile must not be placed on soft ground such as carpet, otherwise it will cause height difference and cannot be charged;
- (4) The position of the charging pile in the scene needs to be marked to prevent incorrect recovery after moving.



13.2 Restricted usage scenarios

Please avoid using Hermes chassis in the following scenarios to avoid chassis failure or damage.

- (1) Overrun/heavy transportation

Do not put in items that exceed the maximum weighing parameter value to avoid affecting the normal use of Hermes. Please refer to the information in the product parameter table for the maximum load-bearing parameter value.

- (2) Sill height

Please ensure that there are no obstacles more than 20mm in front of Hermes, and the maximum height of Hermes over the sill is 20mm. During Hermes driving, please try to avoid passing through uneven ground or other environments with large height.

(3) Man -made impact

Do not forcefully push or hit the Hermes body when Hermes is in normal use.

(4) Temperature / humidity

Do not place Hermes in places with high temperature, high humidity or water stains.

(5) Ground obstacles

Please ensure that the ground is clean and free of wireless obstacles and sundries.

(6) Outdoor

Do not use the machine outdoors.

(7) It is limited to safe use below 2000m above sea level.

13.3 Faults that cannot be handled temporarily

When the machine encounters a fault that cannot be handled temporarily, you can try the following operations:

(1) Please press the brake button;

(2) Push the machine back to the charging pile;

(3) The machine can be forced to switch on and off in any state after power- on.

*Use only in emergency situations.

13.4 Notes

Notes for storage:

(1) Since the machine contains battery, it should be stored in a cool and dry environment;

(2) For long-term storage (more than 3 months), it is recommended to put it in a dry environment with room temperature of 10-25 °C and no corrosive gas;

(3) Hermes shall be charged every 6 months during long-term storage to ensure that the voltage of each battery unit is in the range of 3.6v-3.9v.

Packing notes:

(1) The packaging material must have a certain degree of strength and toughness, and can withstand slight vibration, extrusion, friction and collision during transportation;

(2) There should be padding around the package, which can play a good cushioning role;

Notes for transportation, loading and unloading:

(1) Please handle with care to prevent falling, collision, dragging and inversion;

(2) Stacking needs to be built firmly, compactly, stably and neatly;

Other notes:

(1) Do not treat Hermes violently (such as kicking, pushing, pulling);

(2) Do not spill liquid on the machine;

(3) Do not use the automatic recharge function on the soft carpet with a subsidence of more than 2cm;

(4) It is recommended to start the equipment on the charging base;

(5) Do not change the inside of the machine without authorization;

(6) In environments with many high-transmittance materials, please use auxiliary protection functions, such as virtual walls.

14. Maintenance

1.General maintenance

(1) Radar cleaning: When the machine is shut down and not working, check the surroundings of the radar to ensure that there are no obstructions.

(2) Universal wheel cleaning: When the machine is shut down and not working, gently lift the chassis, wipe the universal wheel with a soft dry cloth, and remove the surrounding foreign matters.

(3) Depth camera lens cleaning: Please wipe the lenses of the two depth cameras with a soft dry cloth when the machine is powered off.

(4) Cleaning the charging pile: Please wipe the charging pile and charging electrode with a soft dry cloth when the power is off.

(5) Collision bar cleaning: Please wipe the collision bar with a soft dry cloth when the power is off, and ensure that there are no wires, paper scraps and other foreign objects stuck on the anti-collision bar.

2. Maintenance cycle

For the maintenance of the main engine, it mainly includes depth camera lens inspection, collision bar inspection, clearance inspection around the radar, foreign matter inspection around the driving wheel and universal wheel, charging pile inspection, etc. The time interval of the maintenance cycle can be appropriately adjusted according to the environment, frequency, intensity and temperature of the machine.

| Hermes maintenance schedule | | | Time interval | | |
|-----------------------------|-------------------|-------------------|---------------|--------|--------|
| NO | Name | Maintenance level | Year | Month | Week |
| 1 | Depth camera lens | Clean | -- | -- | 1 time |
| 2 | Collision bar | Clean | -- | -- | 1 time |
| 3 | Around the radar | clearance | -- | 1 time | -- |
| 4 | Universal wheel | Clean | -- | -- | 1 time |
| 5 | Driving wheel | Clean | -- | -- | 1 time |
| 6 | Charging pile | Clean | -- | 1 time | -- |
| 7 | Machine body | Overhaul | 1 time | -- | -- |

14-1 Hermes maintenance schedule

15. Common faults and troubleshooting

When an abnormality occurs during Hermes operation, please refer to the following table or page tips to solve the problem:

| NO | Fault prompt | Solutions |
|----|---|---|
| 1 | Collision bar abnormal | Please check whether the collision bar is jammed, and tap the anti-collision bar several times to return the anti-collision bar to its position. |
| 2 | Hermes battery low | Please press the brake release button and push the machine back to the charging point to charge. |
| 3 | The charging point cannot be charged | Please check whether the power cord plug of the charging point is inserted into the socket and whether the indicator light of the charging point is on normally. |
| 4 | Unable to power on | Please check whether the charging point is connected to the power supply. After the charging point and Hermes are connected normally, if it cannot be solved, please contact the after-sales service department. |
| 5 | Hermes cannot be charged on the pile | Please try again on the charging pile. If you cannot solve it, please contact after-sales service. |
| 6 | Unable to go back to the charging point | 1. Please confirm whether the position of the charging point has been moved. If the position has been moved, please contact the after-sales department. 2. Please confirm whether there is a slope at the position of the charging point. If there is a slope, please contact the after-sales department. 3. Please push Hermes back to the charging point and try to restart Hermes. |
| 7 | Unable to get in / out of the elevator | 1. Please confirm whether there are obstacles in the elevator. 2. Please confirm the internet signal near the elevator. 3. Please push Hermes back to the charging point and try to restart Hermes. |
| 8 | Universal wheels rotate intermittently | Please check whether there are any foreign objects such as threads, cards, etc. around the universal wheels and the driving wheels. If there are foreign objects, please clean them. |
| 9 | Machine can't walk | Please check whether the drive cable is connected normally. If it cannot be solved, please contact the after-sales service. |
| 10 | The light strip does not light up | Please check whether the connecting wire of the light strip is connected normally. If it cannot be solved, please contact the after-sales service. |

16. Product Executive Standards and certificates

16.1 Product executive standards

GB 4943.1

GB/T 15706

GB/T 16855.1

GB/T 37283

GB/T 37284

*Please do not use this product beyond the limits of the manual to avoid or cause damage to Hermes.

*Please refer to the real object. We reserve the right to update the product without notice.

*Product manual version v1.0.

16.2 Certificate

Company name: Shanghai Slamtec Co., Ltd

Company Address: Unit 01, 2nd Floor, Building E, Shengyin Building, No.666 Shengxia Road, China (Shanghai) Pilot Free Trade Zone.

Contact information: (+86) 021 68581569