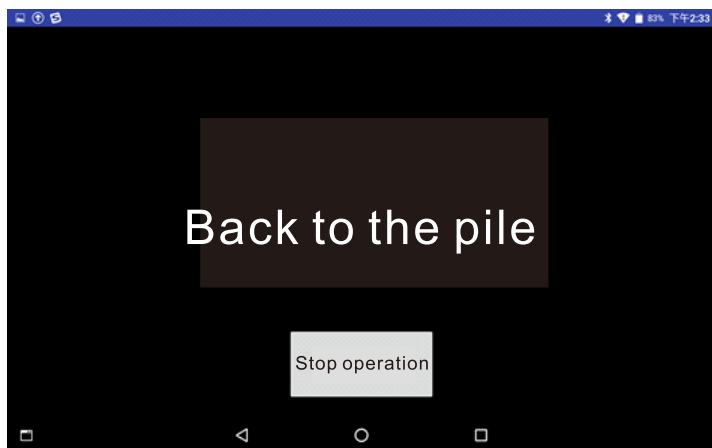


The left side bar displays the saved points. Long press to delete the corresponding points. The path is displayed on the map. Green is the starting point and blue is the point on the path;

Click the "hide point" button again to hide the point and path.

4. Back charging

When the power is less than 25%, it will automatically trigger the back charging, or manually click "back charging" to control the robot back charging;



Click "terminate exit" to terminate the pile return.

Pay attention



When using, people, animals and plants should leave the site and avoid direct contact with eyes and skin

During the operation of this product, if there are (bonsai, mahogany, antique calligraphy and painting, silk and other valuables) in the disinfection space, please remove the disinfection site as far as possible or protect it from the light, so as to avoid the damage of articles caused by direct ultraviolet radiation or ozone. After disinfection, it is recommended to ventilate for 30 minutes, and unplug the power plug at the same time.



Zhongshan Baijia Dagu Electronic Technology Co.,Ltd

BJDG-XD102 STERILIZATION ROBOT INSTRUCTIONS

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Contents

Product introduction.....	1
Technical parameter.....	2
Product appearance diagram.....	4
Basic operation.....	5
Battery replacement instructions.....	6
Software operation instructions.....	6
Scan map.....	8
Fixed point patrol.....	8
Display fixed point.....	9
Back charging.....	10
pay attention.....	10

Product introduction



The disinfection and sterilization robot is a general-purpose wheeled chassis combined with a disinfection machine and ultraviolet sterilization lamp. It is suitable for shopping malls, families, schools, office areas and other places where sterilization can be blocked on flat ground; the robot is equipped with laser radar, which can realize omni-directional scanning and ranging detection of the surrounding environment, carry out planned disinfection and sterilization according to the obtained contour map, so as to avoid adverse effects caused by close tracking contact of human body. The robot is driven by high density lithium battery, which is maintenance free and has a long cycle.

In the aspect of killing performance, the car body is equipped with disinfecting sprayer and ultraviolet lamp, which can effectively kill bacteria and pathogenic microorganisms in environment, air and air. The accumulated intensity of ultraviolet lamp is 936UW/c: the radius of coverage is not less than 6 meters, and the disinfectant area of the sprayer can reach 120. It can achieve 360 degree omnidirectional coverage.

Technical parameter

Body parameters

Size	Chassis dimensions (mm)	635*486*1530
Weight	Including battery	50KG
Power Supply	Battery	Ternary lithium battery
	Battery capacity	24V/40Ah
	Charging time	≤2H
	service life	80% after 300 cycles
	Maximum charging voltage	29.4V
	Endurance (no load)	6H
Drive wheel	Size (wheel diameter * wheel width mm)	200*50
	Material Science	Rubber
	Power	150W
	Maximum speed	250r/min
	Maximum torque	30NM
Universal wheel	Material Science	Rubber
	Size (wheel diameter * wheel width mm)	50*25
	Radius of rotation(mm)	50
	Single bearing	80KG
Performance	Maximum load	50KG
	Maximum operating speed	0.7m/s
	Navigation accuracy	±50mm
	Direction	360° rotation
Safety Protection	Emergency stop button	Emergency stop
	Human induction	Thermal infrared body sensor
	Remote control function	Configure remote control module remote control

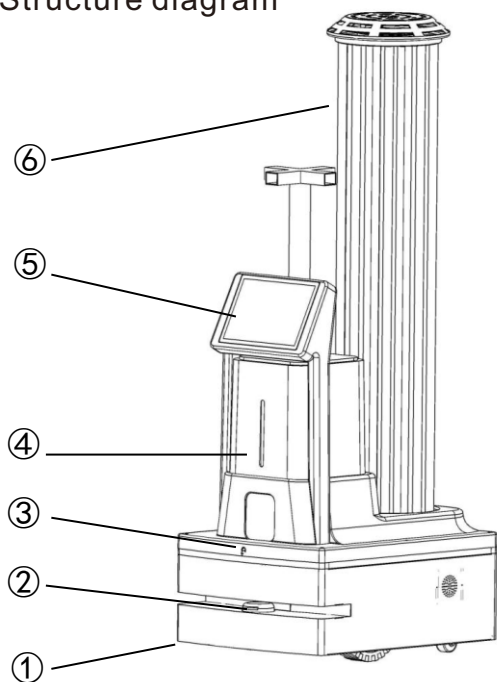
Navigation	Navigation mode	SLAM Navigation
	Path planning	Automatic planning / manual route planning
	Navigation sensor	Lidar (16m)
Signal Communication	wireless network	2.4G/4G WiFi
	Debugging port	Ethernet RJ45
	USB	USB2.0
	Wireless transmission	200M
Environmental Science	Ambient temperature	0℃-45℃
	Ambient humidity	Relative humidity 5-95% (House frosting)
	Operating environment	Indoor use only (no dust and corrosive gas)
	Protection level	IP20
	Antiskid coefficient of ground	≥0.5
	Ground requirements	Concrete level ground (without water, oil or dust)
Ground conditions	Vertical obstacle surmounting ability	10mm
	Ability to cross gullies	20mm
	Maximum climbing angle	5°
Disinfectant spray part	Capacity	15L
	Mist density	1500ml/h
	Applicable area	60-120 m²
Ultraviolet part	UV intensity	117UW/CM² (each)

Design parameters of charging pile

Charging post	Size (mm)	400*128*250
	input voltage	AC220V
	output voltage	29.4/7A
	Rated power	200W

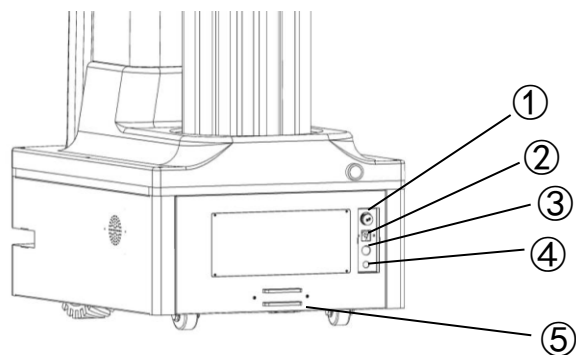
Product appearance diagram

Structure diagram



- ① Robot body
- ② Lidar
- ③ Human induction
- ④ Disinfectant sprayer
- ⑤ Operation panel
- ⑥ New UV lamp

Back



- ① Main power switch
- ② USB interface
- ③ Emergency stop switch
- ④ Charging port
- ⑤ Automatic charging touch bar

Basic operation

1. Add disinfectant:

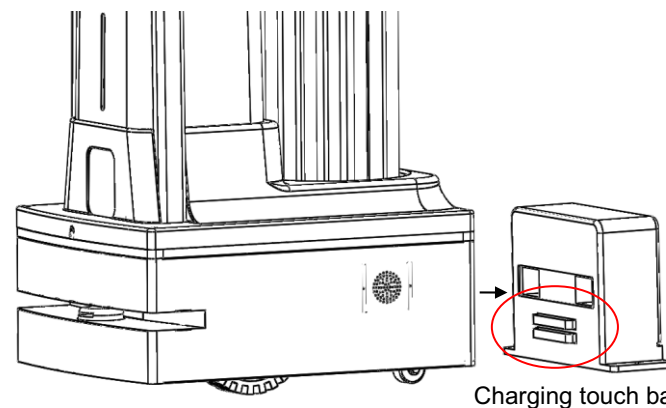
Open the cover on the rear side of the sprayer, pour the disinfectant (PH5.0-6.9) into the medicine box, and then close the lid.



2. Power on operation:

Turn on the "main power switch" to start the machine, remote control can turn on the ultraviolet lamp, and start disinfection and sterilization according to the software operation instructions. (please be familiar with product appearance configuration before startup)

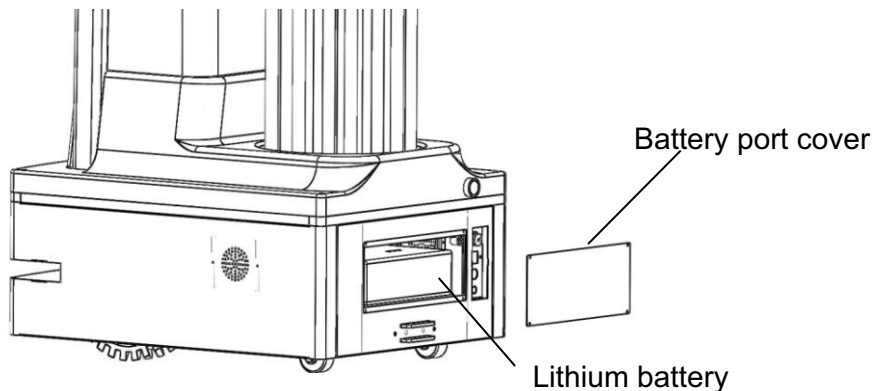
Note: charging instruction: put the charging pile in a proper position, plug in the plug, and the robot will recharge automatically.



Battery replacement instructions

The following operations shall be carried out when the main power supply of the machine is turned off, and the machine body and the ultraviolet lamp stop working.

1. Loosen the four screws at the back of the fuselage and remove the battery port cover plate.

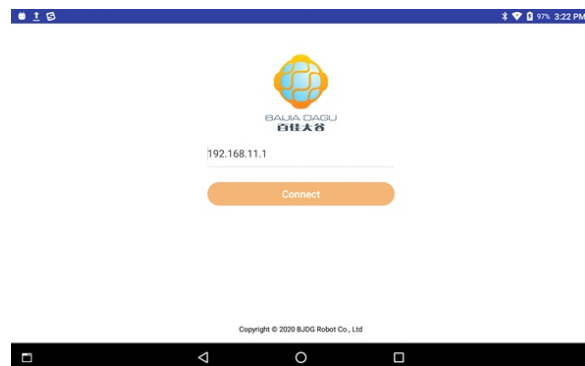


2. Find the cable connecting the battery, unplug the separation adapter, and then take the battery out of the body.
3. Finally, insert the new battery into the original position, connect the adapter, lock the battery port cover plate and complete the replacement.

Software operation instructions

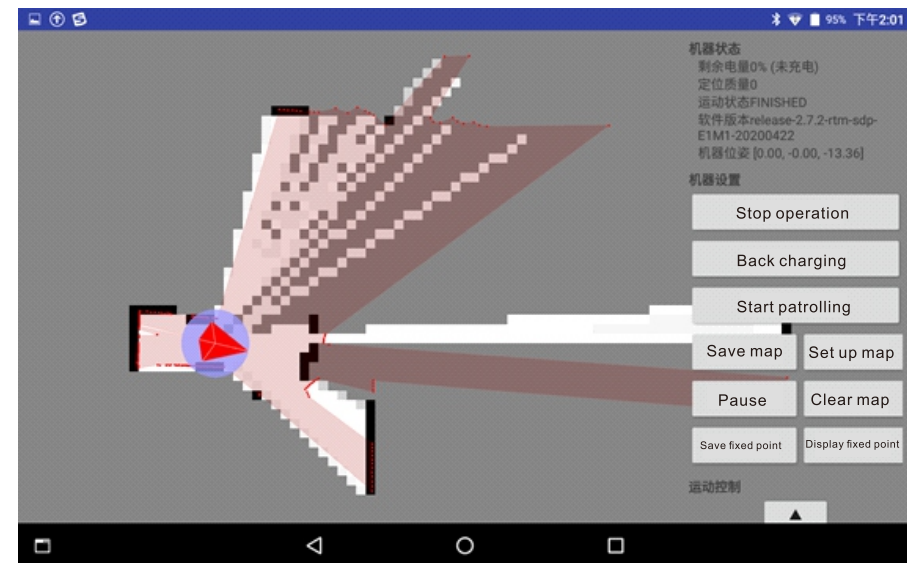
1、 Connect

Open the "bjdg robot" app and enter the control program. The interface is as follows:



Generally, the default IP address does not need to be modified. Click "connect slamware" to enter the control interface. If the connection fails, a pop-up window will pop up. Please check whether the network is connected; Mobile app connection, search for WiFi name BJDGRobot_XXXX, the password is bj12345678, you can enter the app after connecting WiFi successfully;

2. Operation



In the middle of the interface is a map, the left side shows the robot status, machine settings, motion control and running speed, etc;

Start patrolling - start patrolling along the preserved points;

Back charging - back charging pile;

Stop operation - stop all current operations;

Save map - save map to local;

Set up map - load locally saved map;

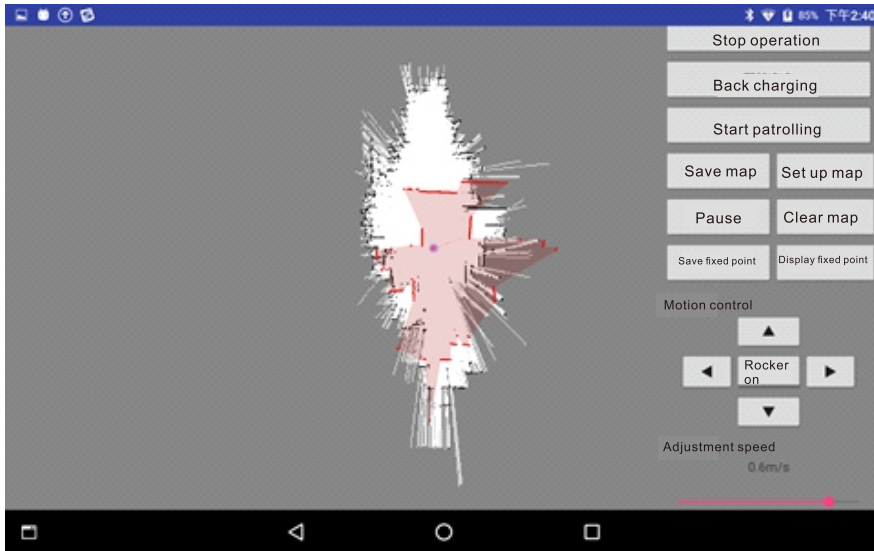
Clear map - clear the current map and saved points;

Save fixed point - manually save the current position of the robot as a fixed point;

Display fixed point / hide fixed point - display the saved fixed point and route, and then click Hide;

Pause / continue drawing - switch drawing status;

Motion control and adjustment speed:



1. Scan map

The first step of robot operation is to scan the map. In the state of robot drawing, the robot can automatically scan the map of its environment by controlling its motion. There are two ways to control robot motion to scan the image:

- ① Via left motion control
- ② By clicking on the map, the robot will go to the corresponding point on the map

Try to use the second way as much as possible, because the moving points will be recorded during the scanning process, and the patrol route will be generated automatically, which will be used later.

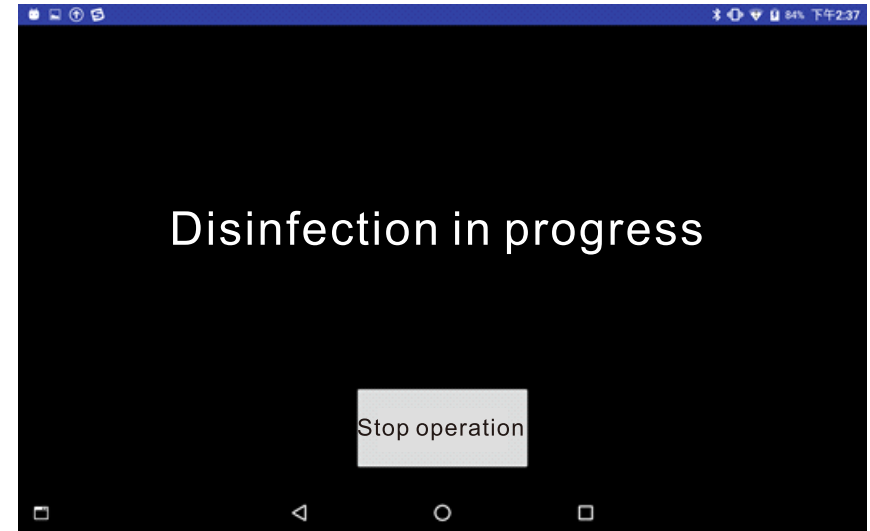
When the map is scanned, click "save map" to save the map. If you do not need to change the map, you will not need to scan the map every time you use it.

Note: click "clear map" before rebuilding the map to clear the previous map data!

2. Designated patrol

By default, under free navigation, first click "set map", load the saved map, make sure that the saved map is the current environment scanning map, then click to start patrolling, and the robot will patrol and disinfect according to the scanning route;

Click "terminate exit" to stop patrolling;



Note: make sure the robot starts at a fixed charging point every time!

3. Display fixed point (patrol path)

Click the "display fixed point" button to display the saved fixed point and path, as shown below:

