AGIBOT A3 Series User Manual

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Welcome to use

Thank you for choosing the AGIBOT A3 Robot.

This user manual helps you quickly get started with the AGIBOT A3 Robot (hereinafter referred to as "the Robot"), and provides detailed guidelines for operation and maintenance to ensure an optimal user experience. Should you have any problems during use, please contact our service hotline or E-mail us. Our professional technical support team will provide you with timely assistance.

Read User Manual: https://www.agibot.com/filepage/290.html

Contact After-sales Service: https://www.agibot.com/filepage/292.html

1. Important Notice

1.1 Safety Guidelines

1. **Know the Product**: Before using the Robot for the first time, please read the manual to fully understand its functions, operating procedures, and all safety instructions.

2. **Environmental Requirements**: Operate the robot only on flat, dry and stable surfaces. Do not use it in environments with extreme high or low temperatures, high humidity, steep slopes, sharp drops, fragile ground or strong vibration.

3. **Regular Inspection and Maintenance**: Conduct regular maintenance and status checks on the Robot, focusing on key components such as joints, sensors, and the power system, to ensure the equipment remains in good working condition and to prevent safety hazards caused by component aging or damage.

4. **Know the Emergency Stop Operations**: Before use, familiarize yourself with the emergency stop operation method to halt the robot promptly in case of emergencies. Once the emergency stop is activated, all robot joints will lose support and collapse.

For this reason, strictly observe on-site safety regulations and keep the protective frame in place at all times after an emergency stop. **Do not activate the emergency stop unless necessary.**

5. **Reserve Operating Space**: Before operation, ensure sufficient surrounding space for the robot to move. Do not use it in overly narrow areas or spaces crowded with people and obstacles, to prevent collision and pinching risks.

6. **Electrical Safety**: Before power-on, inspect cables, plugs and sockets to confirm they are intact and free of abnormalities. If a short circuit, overheating or other faults are detected, cut off the power supply immediately.

7. **Prohibit Improper Use**: Use the robot only in compliant and proper application scenarios. Do not operate it for dangerous, illegal or unauthorized purposes.

1.2 Safety Guidelines

1. Pre-Operation Checks

a. Before powering on the robot or initiating any movement, ensure no personnel, debris or obstacles remain in the working area, especially around robotic arms, joints and other moving parts, to prevent collisions and personal injury.

b. Operators shall inspect the robot for normal status before startup and confirm the completion of system self-check.

2. Standardized Operation and Training Requirements

All operating personnel must receive operating training in advance. Operators shall be familiar with the robot's specifications, standard operating procedures and exception handling protocols, to avoid safety risks arising from improper operation.

3. Maintain a Safe Distance

Keep a minimum 1 meter safe distance from the robot's working area during operation to prevent collision hazards caused by sudden equipment movement. Do not stay within the robot's predicted motion path, especially during high-speed operation.

4. Prohibition of Manual Intervention During Operation

Do not manually interfere with the robot while it is running. If adjustment, maintenance or manual handling is required, confirm the robot has come to a complete stop and is fully powered off before any operation.

5. Load and Component Usage Requirements

a. Operate the robot within its rated load capacity. Do not apply loads exceeding its designed specification limits.

b. When using end-effectors, grippers and other functional components, ensure full compatibility with the target workpiece. Mismatched components may cause extrusion, abnormal stress or permanent part damage.

6. Shutdown Procedures for Abnormal Conditions

In the event of abnormalities, malfunctions or unexpected faults, immediately activate emergency shutdown via the remote control to stop all robot motions without delay.

8. Remote Control Precautions

a. If the robot is equipped with remote control functions, operate it only under stable and secure network conditions. Network interruptions, latency or external intrusion will impair control stability.

b. Remote operators shall adopt real-time monitoring measures to continuously keep track of the robot's running status and on-site environment, so as to ensure the safety of remote operation.

2. AGIBOT A3 Overview

2.1 Unpacking List

No.	Component Name	Quantity
1	Robot Main Body	1
2	Battery Charger	1
3	Magnetic Charging Connector	1

4	Remote Control	1
5	Protective Helmet	1
6	Lavalier Microphone	1
7	Quick Start Guide	1
8	Qualification Certificate	1
9	Safety Lanyard	2
10	Lifting Rings	2
11	Silicone Hand (Fist Gesture)	2
12	Accessory Kit	1

2.2 **Product Introduction**

The AGIBOT A3 series products feature 31 to 57 degrees of freedom (varies by model and configuration), enabling flexible movement and high-precision posture control. The following details the specific configuration and functions of the AGIBOT A3.

• The AGIBOT A3 has a total of 31 active degrees of freedom (excluding hands), with 2 in the neck, 7 per arm, 3 in the waist, and 6 per leg. It is equipped with silicone hands and silicone fists.

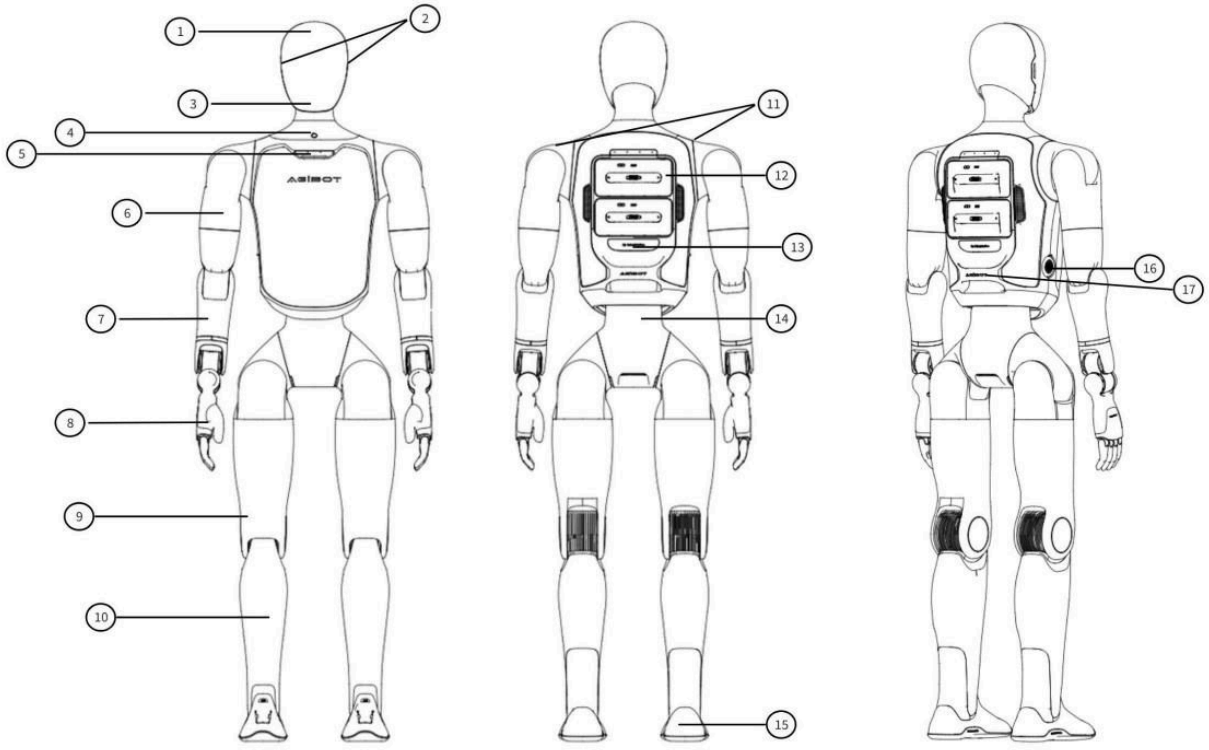
• The perception system is equipped with RGB stereo cameras, GPS, UWB positioning, and shoulder touch sensors.

• The communication system is equipped with Wi-Fi, 4G/5G mobile network, and Bluetooth.

• The interaction system is equipped with omnidirectional microphones, speakers, a curved display, and omnidirectional indicator lights.

• The power system is equipped with a 1152Wh battery, providing a total battery life of 10 hours, including 6 hours of standing operation and over 4 hours of continuous walking. It supports both charging and battery changing modes, with a charging time of ≤2 hours.

2.2.1 **Component Names and Description**



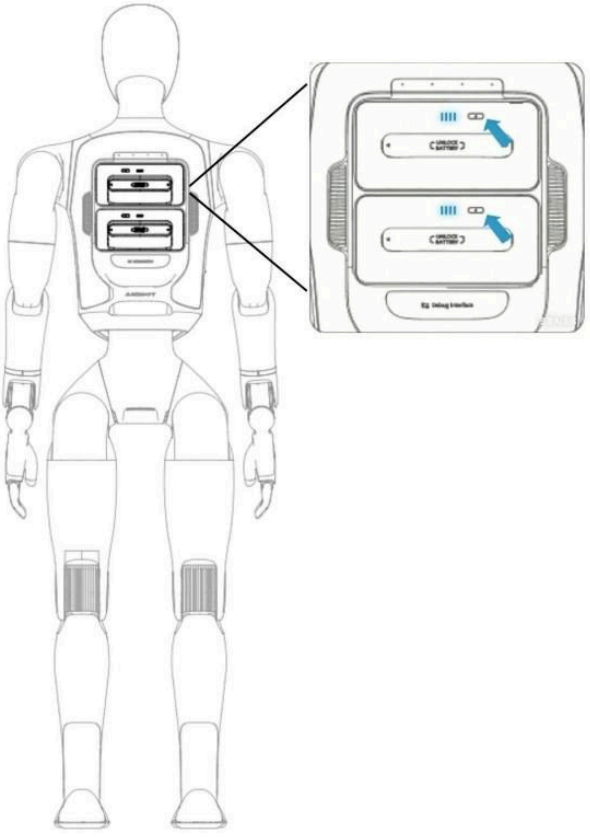
No.	Component	No.	Component	No.	Component

1	Head Display	7	Forearm	13	Maintenance Port
2	Left and Right Speakers	8	Hand	14	Waist
3	Interactive Binocular Camera	9	Thigh	15	Foot
4	Switch	10	Calf	16	Charging Port
5	Microphone	11	Shoulder touch sensor	17	Waist Handle
6	Upper Arm	12	Dual Battery Compartments		

2.2.2 **Battery Indicator**

Note: When using battery power, **closely monitor the battery level**. Low or nearly depleted batteries may **cause the robot to topple** suddenly due to insufficient power. **Recharge or replace the battery immediately when only one indicator remains** to maintain stable operation and avoid injury.

2.2.2.1 **Location of Battery Indicator Lights**



2.2.2.2 **Indicator Status Description (Working)**

Battery Light Status (Working)	Battery Level	Status Description
All LEDs off	0%	No power
LED1 on, LEDs 2-4 off	1% ≤ Battery Level < 25%	Critical Low Power (Recharge Immediately)
LEDs 1-2 on, LEDs 3-4 off	25% ≤ Battery Level < 50%	Low Power (Plan for Recharge)
LEDs 1-3 on, LED4 off	50% ≤ Battery Level < 75%	Sufficient power
LEDs 1-4 on	75% ≤ Battery Level < 100%	Full power

2.2.2.3 **Indicator Status Description (Charging)**

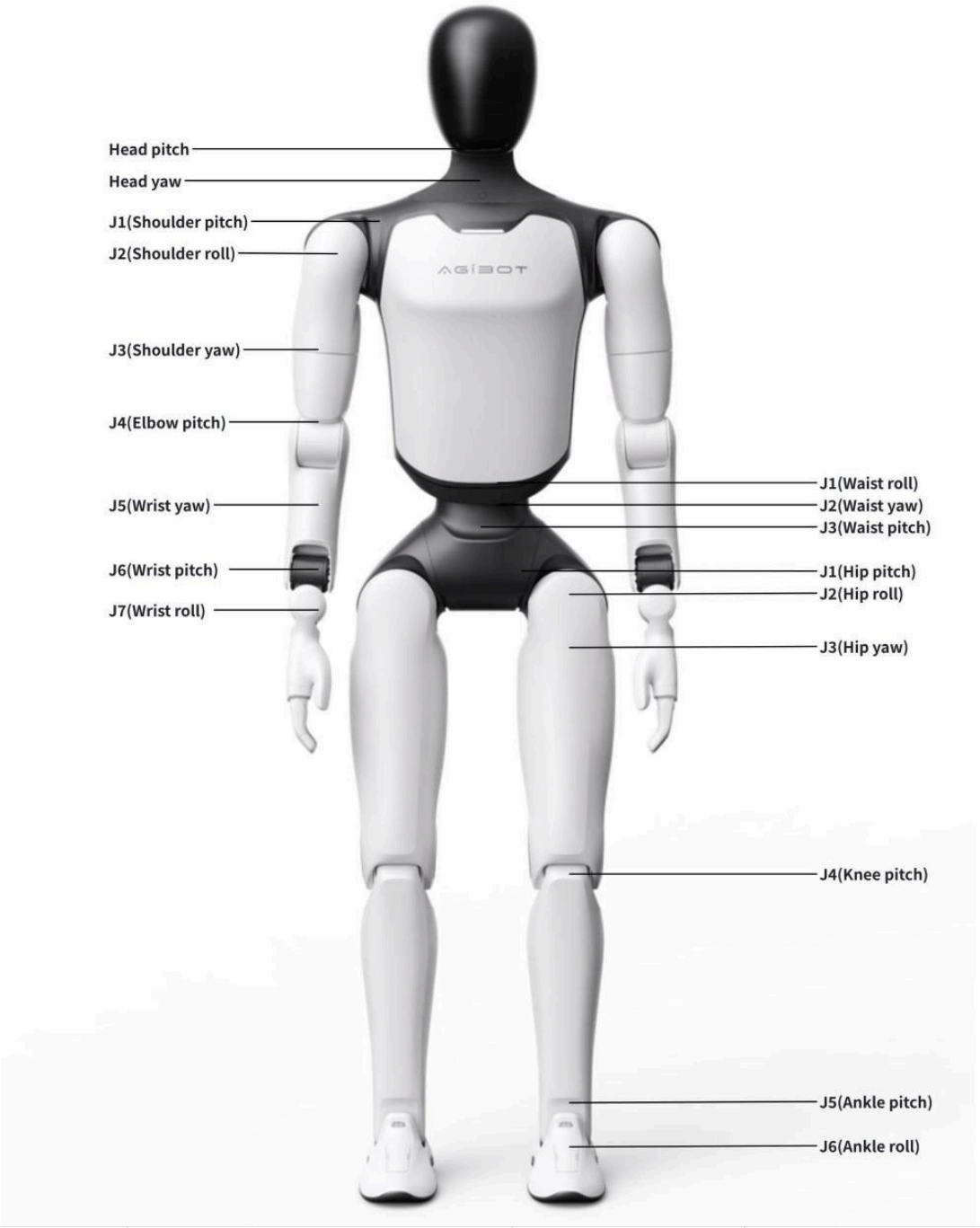
Battery Light Status (Charging)	Battery Level	Status Description

LED1 breathing, LEDs 2-4 off	Battery Level < 25%	Critical Low Power
LED1 on, LED2 breathing, LEDs 3-4 off	25% ≤ Battery Level < 50%	Low Power: Do not disconnect
LEDs 1-2 on, LED3 breathing, LED4 off	50% ≤ Battery Level < 75%	Medium Power: Operable; charge to full recommended
LEDs 1-3 on, LED4 breathing	75% ≤ Battery Level < 100%	Sufficient Power
LEDs 1-4 on	Battery Level = 100%	Charging Complete

2.2.3 **User Debugging Interfaces**

No.	Hardware Expansion Interface	Interface Type	Interface Description
1	Maintenance Port - **Waist**: For debugging and Further development	USB Type-A 2.0	• Supports debugging and development of the **torso** MDU (RK3588)
2	Maintenance Port - **Head**: For debugging and Further development	USB Type-C	• Supports debugging and development of the **head** HDU (RK3588) • Supports connection of microphone receiver
3	Power Interface	USB Type-C	• Supports 5V/3A output, and charging external devices (i.e. Remote Control)

2.3 **Robot Joint Motion Range**

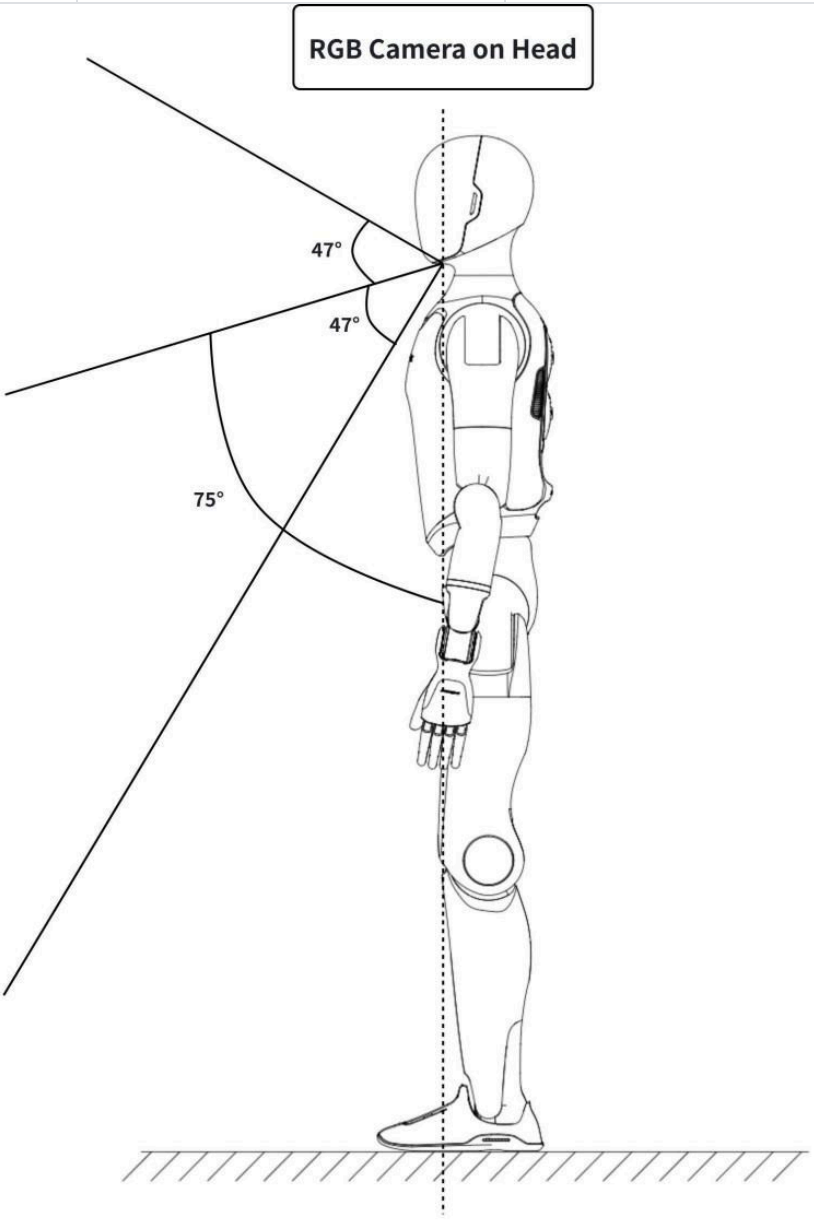


Joint Name	Joint Limit	Joint Name	Joint Limit
Arm	J1 (Shoulder pitch): -170° to 170°	**Waist**	J1 (Waist roll): ±20°
	J2 (Shoulder roll): -91° to 91°		J2 (Waist yaw): ±150°
	J3 (Shoulder yaw): ±160°		J3 (Waist pitch): ±30°
	J4 (Elbow pitch): -60° to 140°	**Leg**	J1 (Hip pitch): -168° to 154°
	J5 (Wrist yaw): ±160°		J2 (Hip roll): -60° to 100°
	J6 (Wrist pitch): ±93°		J3 (Hip yaw): ±158°
	J7 (Wrist roll): ±33°		J4 (Knee pitch): -10° to 148°
Head	Tilt joint (Head pitch): 15° (down), 25° (up)		J5 (Ankle pitch): -52° to 30°
	Rotation joint (Head yaw): ±90°		J6 (Ankle roll): ±20°

Note: Joint Limits are calculated based on structural design parameters. Individual differences may exist between devices, and these data are for reference only.

2.4 Robot Sensor Field of View

Robot Model	Configuration	Capability
AGIBOT A3	Interactive Binocular Camera	Interactive Binocular Camera: Supports visual recognition and response in human-robot interaction scenarios



2.5 Robot Specifications

Robot Specifications		Details
Main Body	Height	1.73 m
	Dimensions	173 cm (H) x 52 cm (W) x 30 cm (L)
	Weight	55 KG
	Active Degrees of Freedom	31
	Neck Degrees of Freedom	2
	Single Arm Degrees of Freedom	7
	Waist Degrees of Freedom	3
	Single Leg Degrees of Freedom	6
Perception System	3D LiDAR	/

	Embodied Operation RGB-D Camera	/
	Terrain Perception RGB-D Camera	/
	Interactive RGB Camera	RGB Binocular Camera
	Panoramic RGB Camera	/
	GPS	Equipped
	GPS RTK	/
	UWB Positioning	Equipped
	Shoulder Touch Sensors	Equipped
Communication	Communication Methods	WiFi, 4G/5G Network, Bluetooth
Interaction	Microphone	Omnidirectional Microphone Front and Rear 8-Microphone Array
	Speaker	Equipped
	Face Screen	Curved Screen
	Indicator Lights	Omnidirectional Indicator Lights
Performance	Knee Joint Peak Torque	320 N·m
	Movement Speed	Max Daily Walking Speed: 1.8 m/s Normal Daily Walking Speed: ＜ 1.2 m/s Maximum Laboratory Speed: 2.5 m/s Max Running Speed: 5 m/s
	Single Arm Payload	5 kg
Power and Energy	Battery Capacity	1152 W·h
	Battery Life	10 hour * measured with standing / walking ratio = 1:1. * Battery life measurement is affected by walking speed and load.
	Charging Methods	Supports direct charging and battery swapping
	Charging Time	≤2 hour
	Charging Input Voltage	110-220 V
Computing Power	Basic Computing Board	RK3588 * 2
	Advanced Computing Board	/
Others	Wireless Remote Control	Equipped
	OTA Update	Supported
	Further Development	Supported

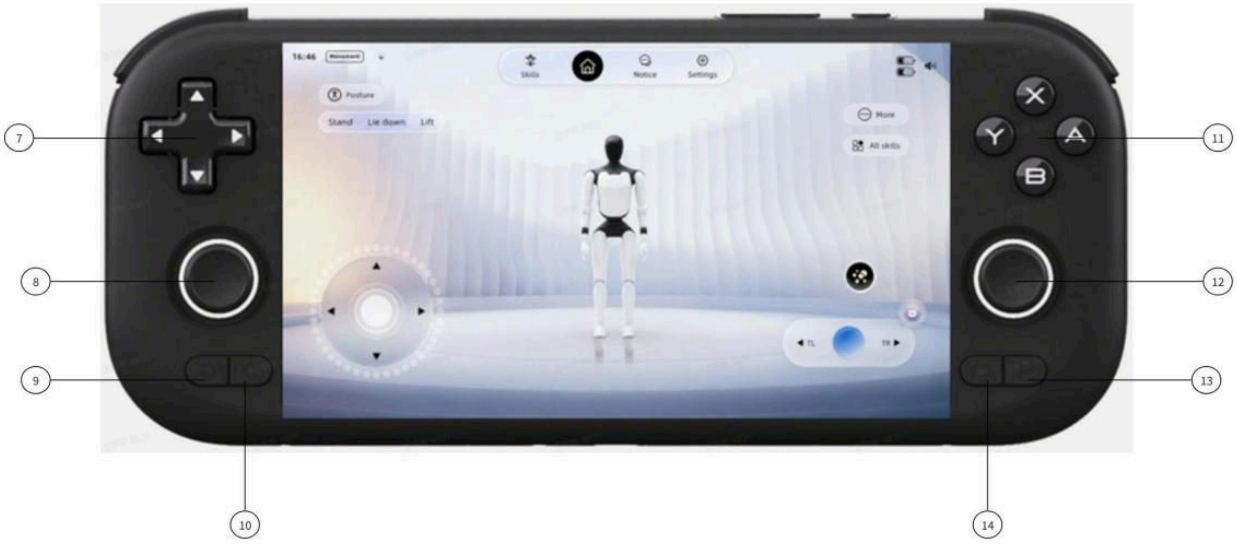
3. **Introduction to Remote Control**

3.1 **Remote Control Exterior Design**



3.2 Remote Control Button Layout





No.	Name	No.	Name
1	Left Trigger (L2)	8	Left Joystick (L3)
2	Left Shoulder Button (L1)	9	Back
3	Power Button	10	Home
4	Volume	11	A/B/X/Y
5	Right Trigger (R2)	12	Right Joystick (R3)
6	Right Shoulder Button (R1)	13	Start
7	D-Pad	14	Select

3.3 **Remote Control Charging Instructions**

Charging Method: The remote control supports charging via a USB-C cable. Do not use a high-power charger, as this may degrade the remote control's performance.

Battery Life: The remote control typically lasts about **4 hours** on a single charge. A full charge takes **3-4 hours**. Actual battery life is affected by various factors, and the specific duration depends on actual usage.

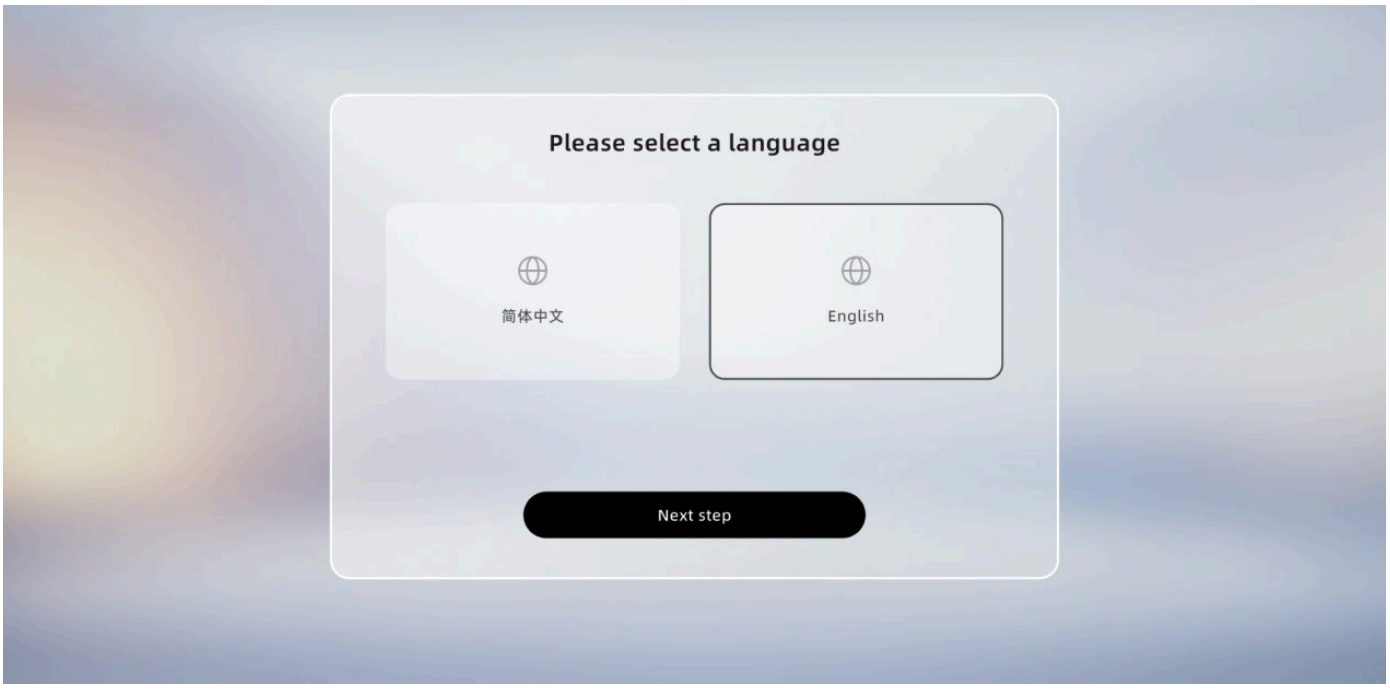
Precautions:
1. When using the remote control to operate the Robot, **closely monitor the Robot's battery level** . Low battery may prevent switching motion control modes, which could lead to the Robot falling unexpectedly.
2. Use a charger that meets safety standards to charge the remote control. It is recommended to use a 5V/1A or 5V/2A charger to prevent damage from overcharging.

4. **Usage Instructions**

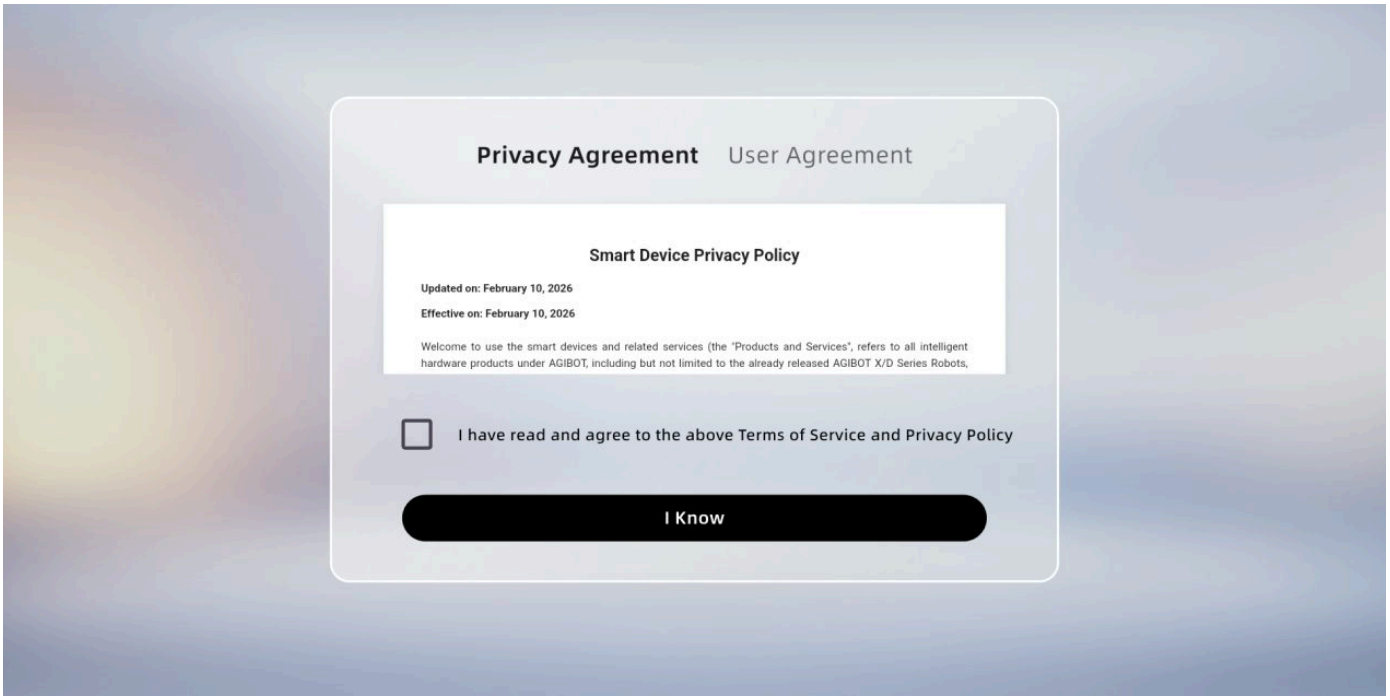
4.1 AimMaster Interface

4.1.1 General Guide (How to Connect the Robot)

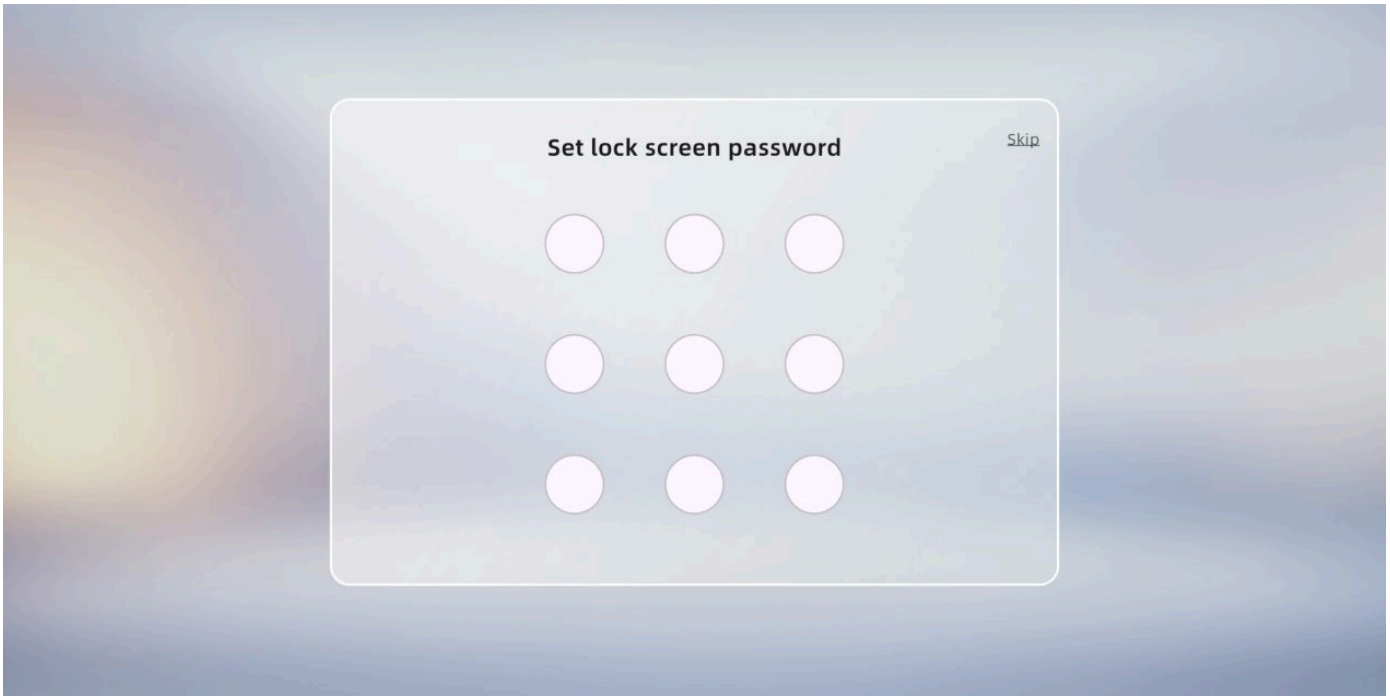
Step 1: Language Selection (Required for First Connection)



Step 2: Privacy & User Agreement (Required for the first connection)



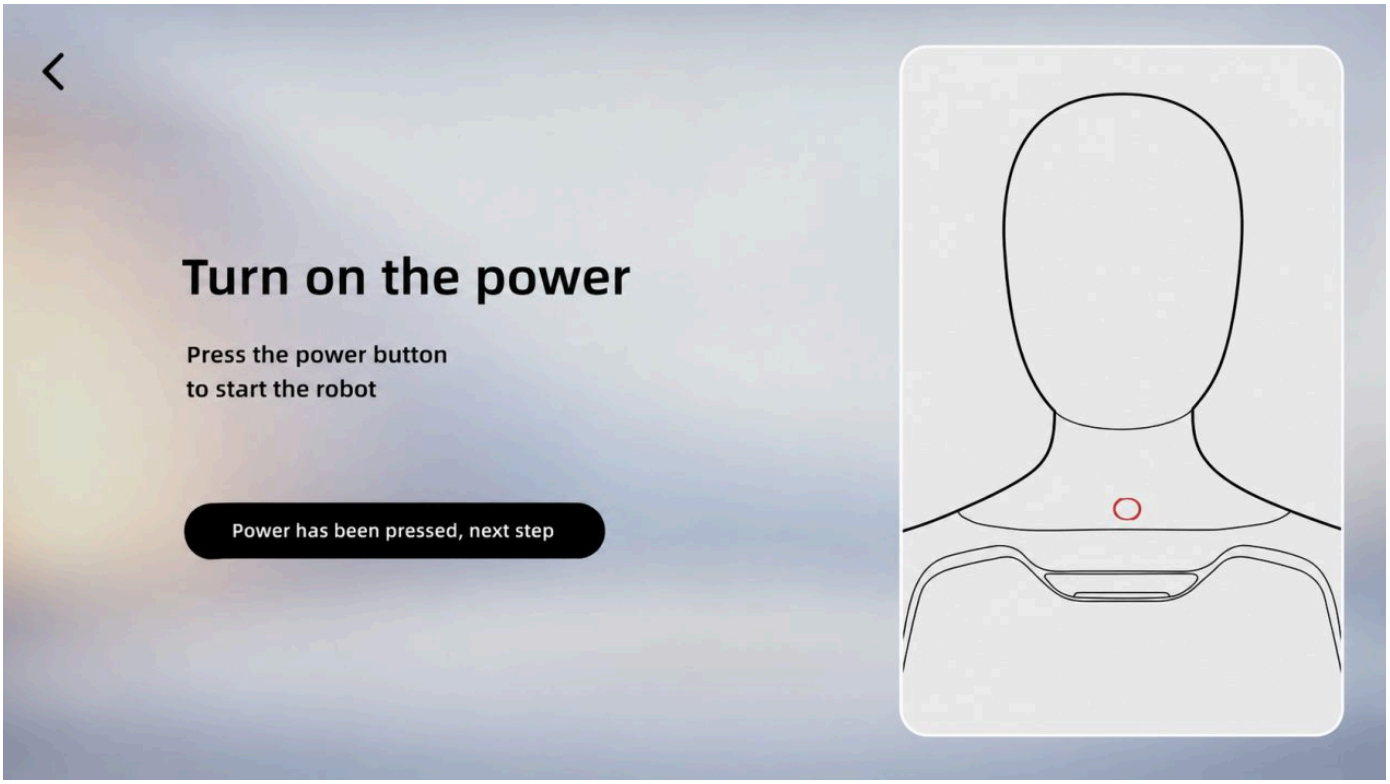
Step 3: Lock screen password setting (required for the first connection)



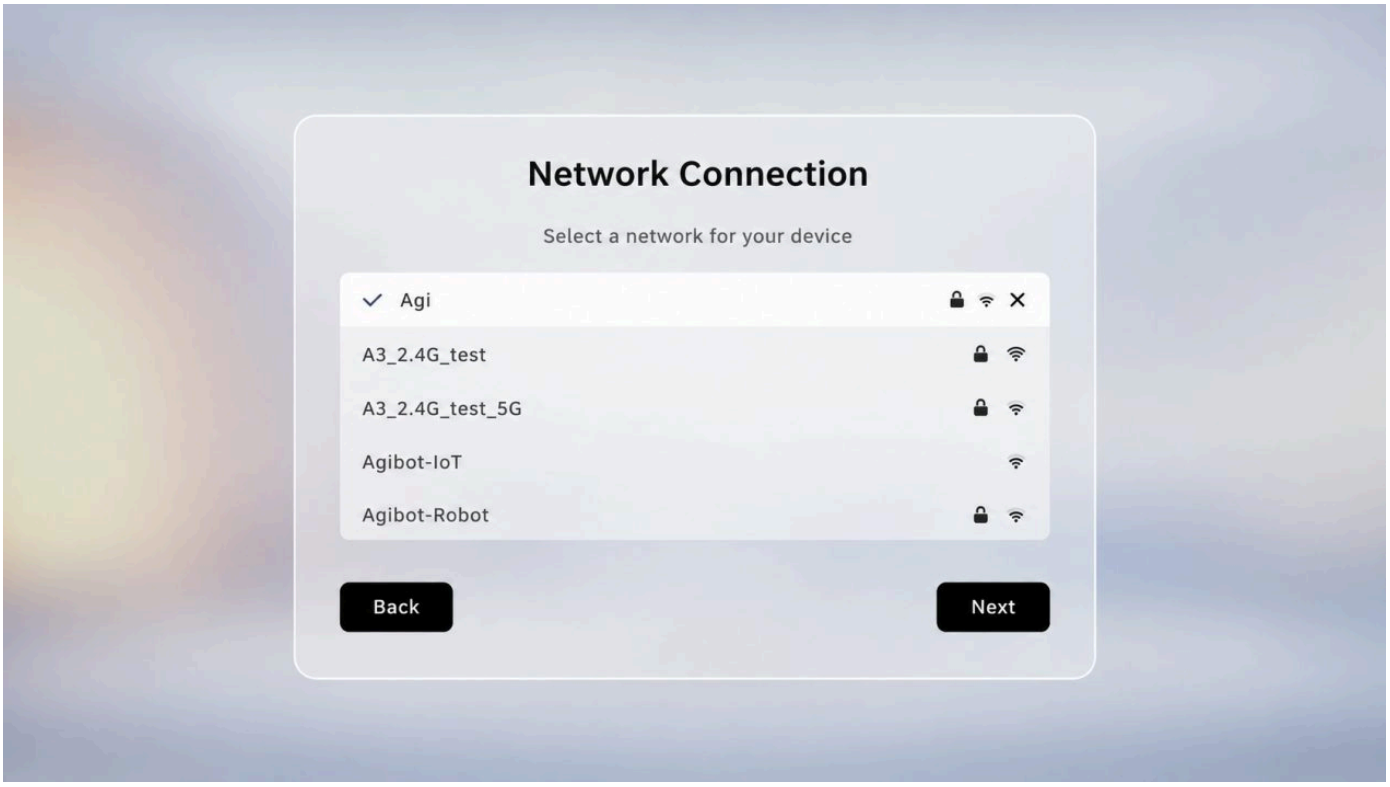
Step 4: Select the robot type



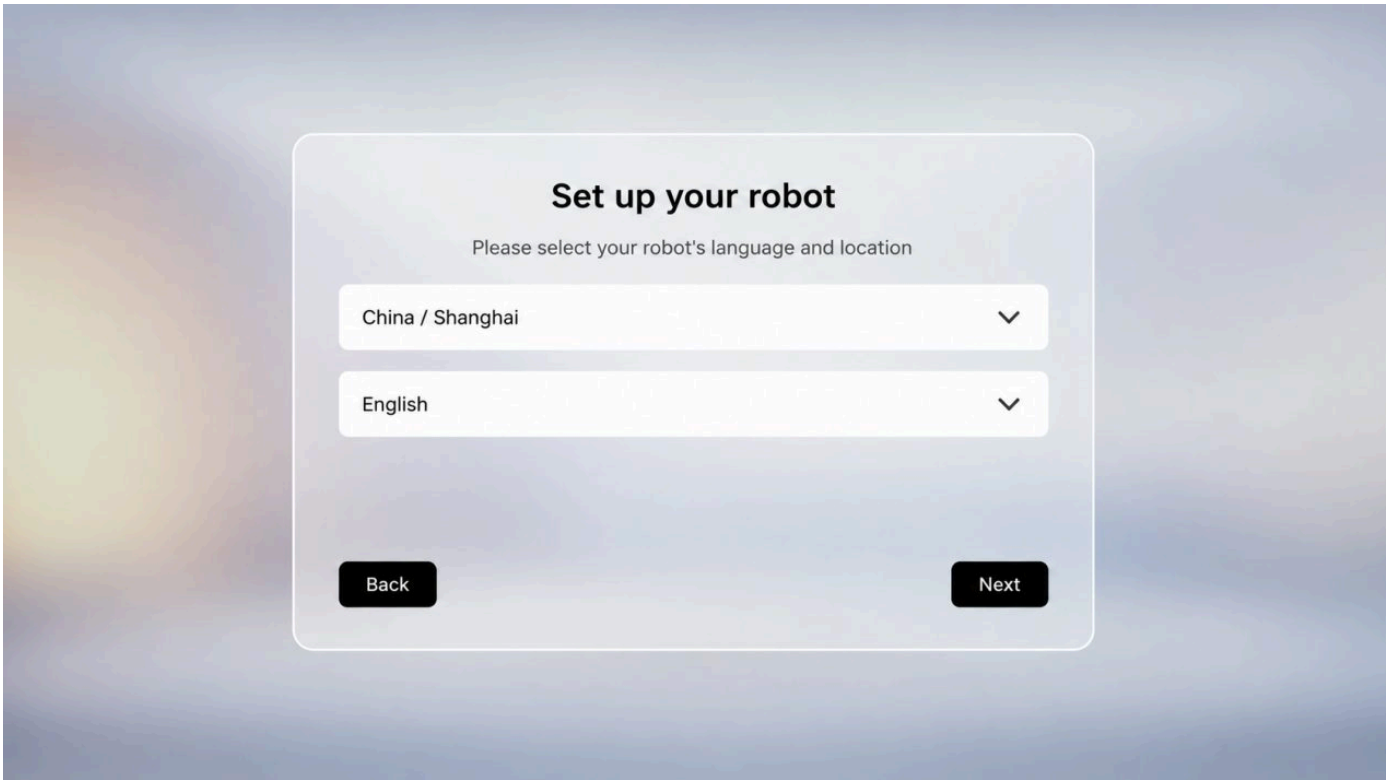
Step 5: Turn on the power



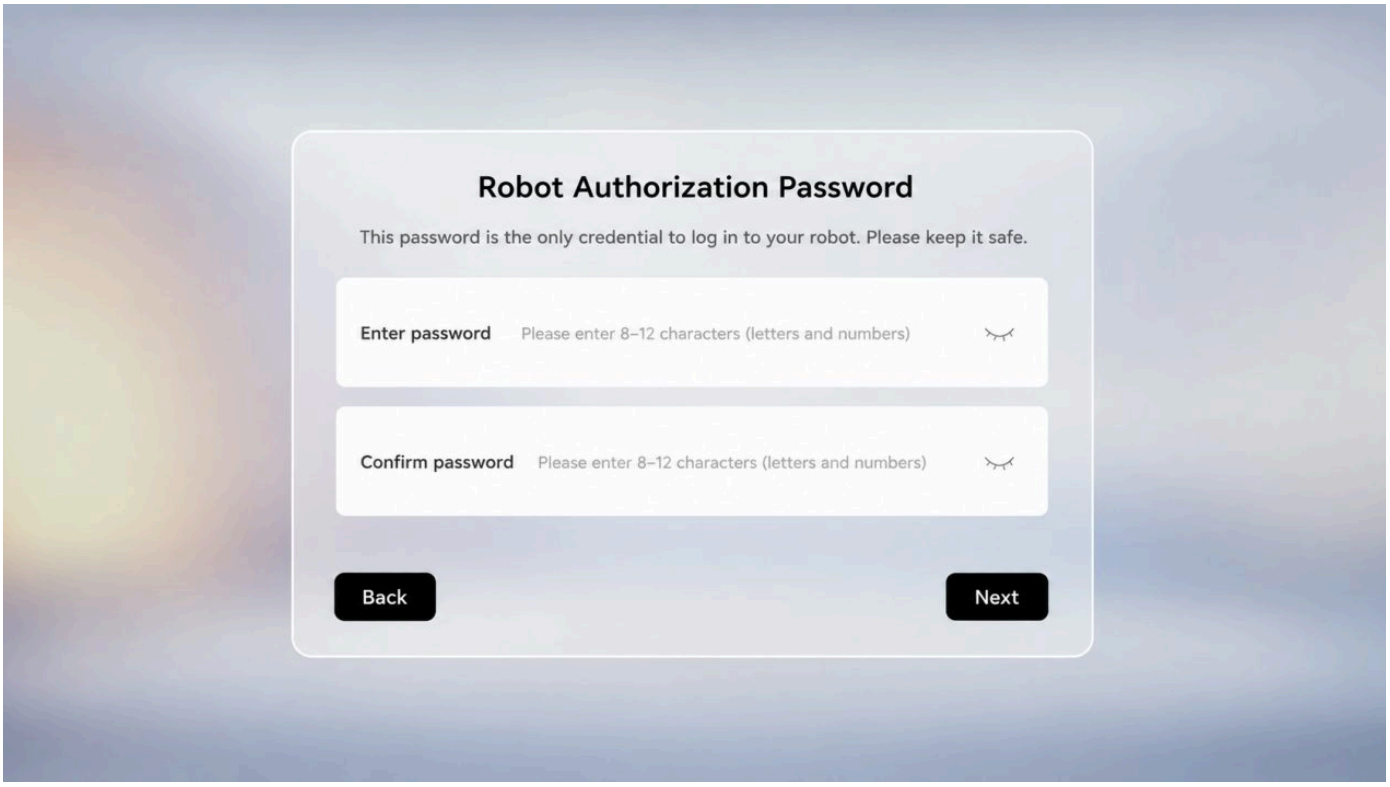
Step 6: Network connection (required for the first connection)



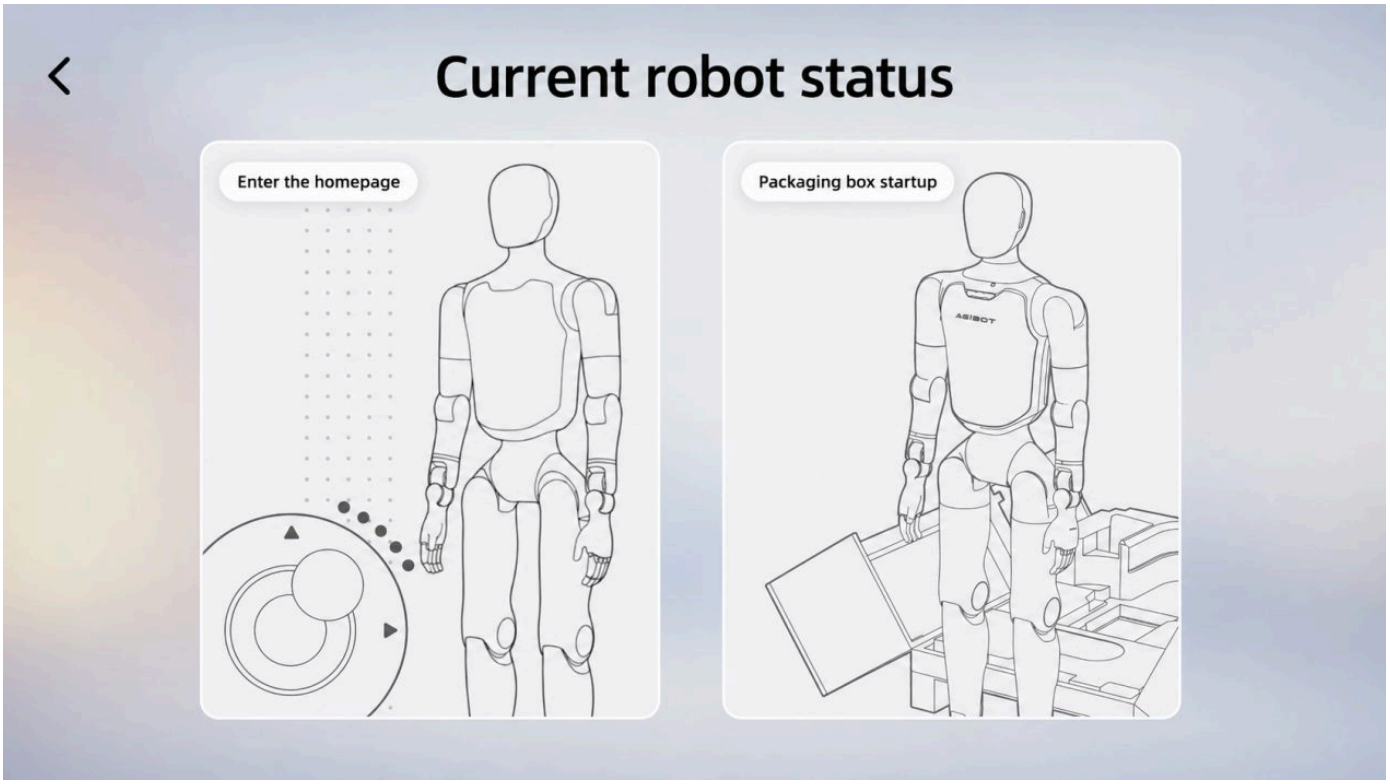
Step 7: Select the robot's language and location (required for the first connection)



Step 8: Robot authorization password (required for the first connection)



Step 9: Select the robot's posture



Step 10: Enter the home page

For detailed functionality, refer to the App User Manual https://agirobot.feishu.cn/wiki/HQTdwidb5iPBplkk9iDcpLEPnEe

4.2 Startup Process

4.2.1 Packaging Machine Startup

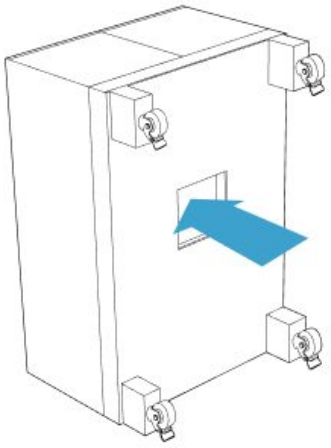
Step 1: Activate the battery

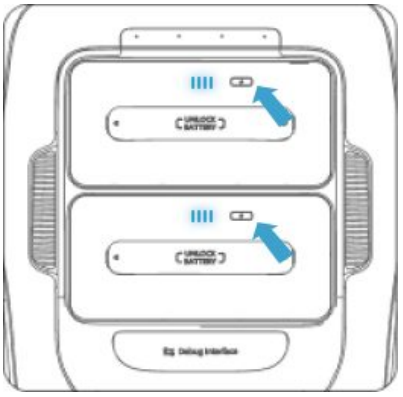
> Note:
> This activation step is only required when opening the package for the first time or when the battery pack is in storage and transportation mode.

Stand the packaging box upright, open the bottom window, **short press and then long press** the power button of each of the two battery packs, **until all the indicator lights of the battery packs light up in sequence**, indicating successful activation, and then close the bottom window.

Step 1-1: Stand up the packing box and open the bottom window

Step 1-2: Activate two battery packs

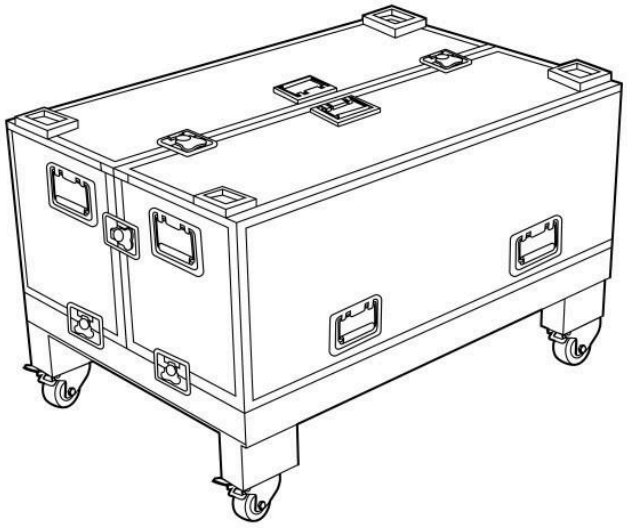




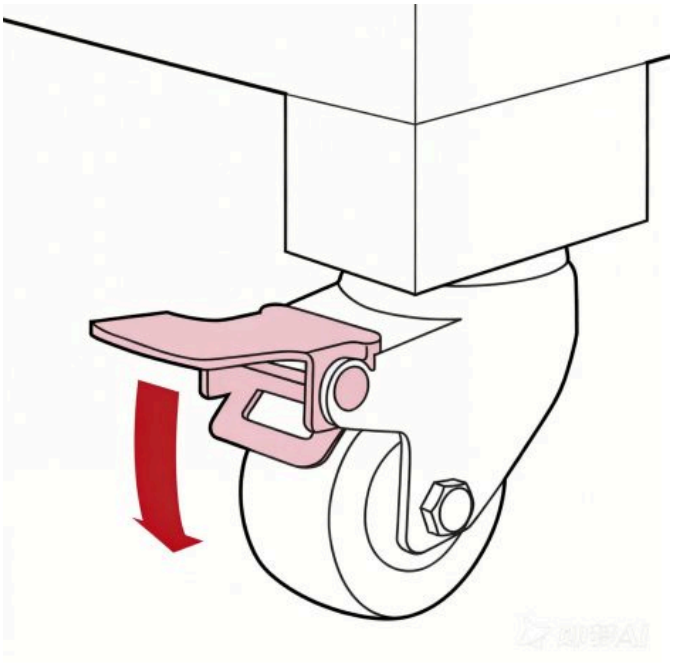
Step 2: Open the package

Lay the packing box flat, lock the wheels at the bottom of the packing box after confirming that there are no obstacles in front, then open the top cover of the packing box and remove the middle layer and hip-cover foam, ensuring that there are no items above the robot.

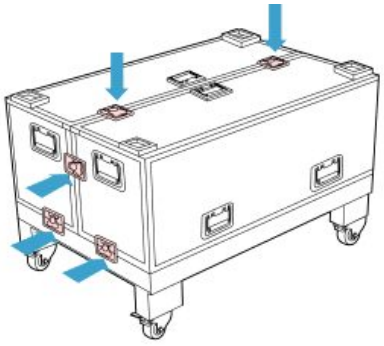
Step 2-1: Place the packing box flat



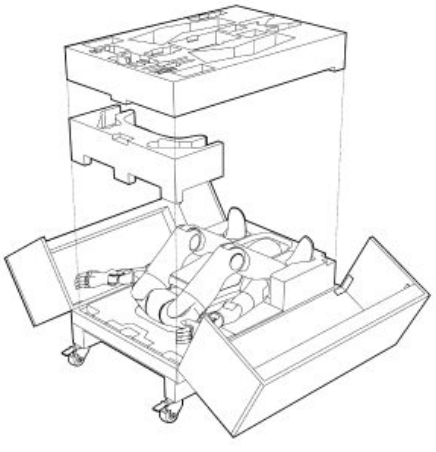
Step 2-2: Lock the wheels at the bottom of the packing box



Step 2-3: Unlock and open the top cover of the packaging box

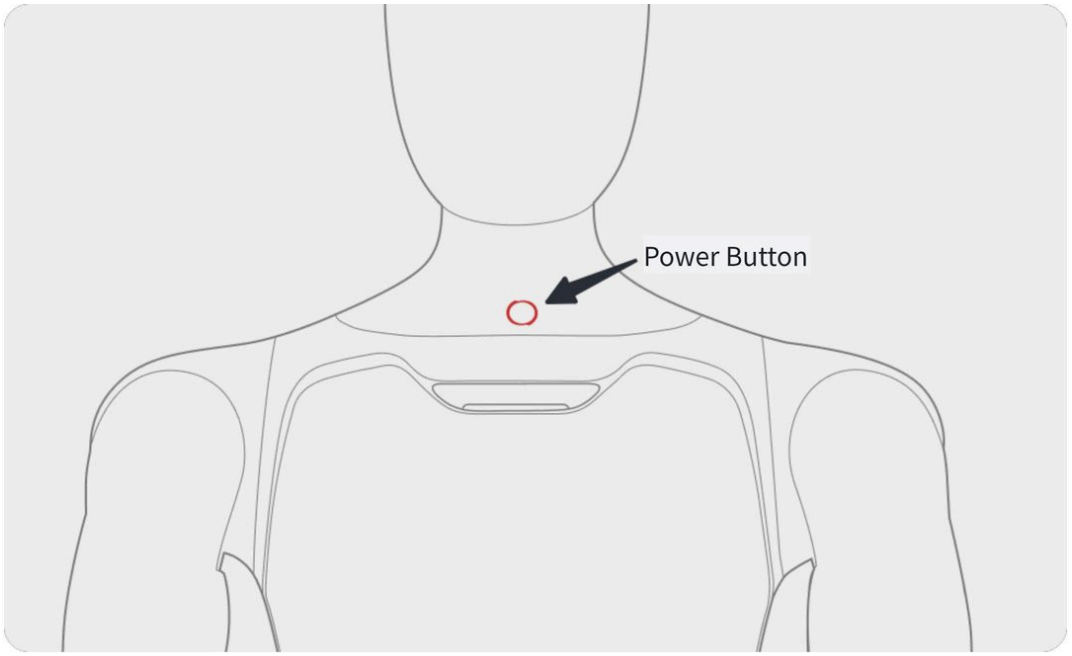


Step 2-4: Remove the middle layer and hip-cover foam



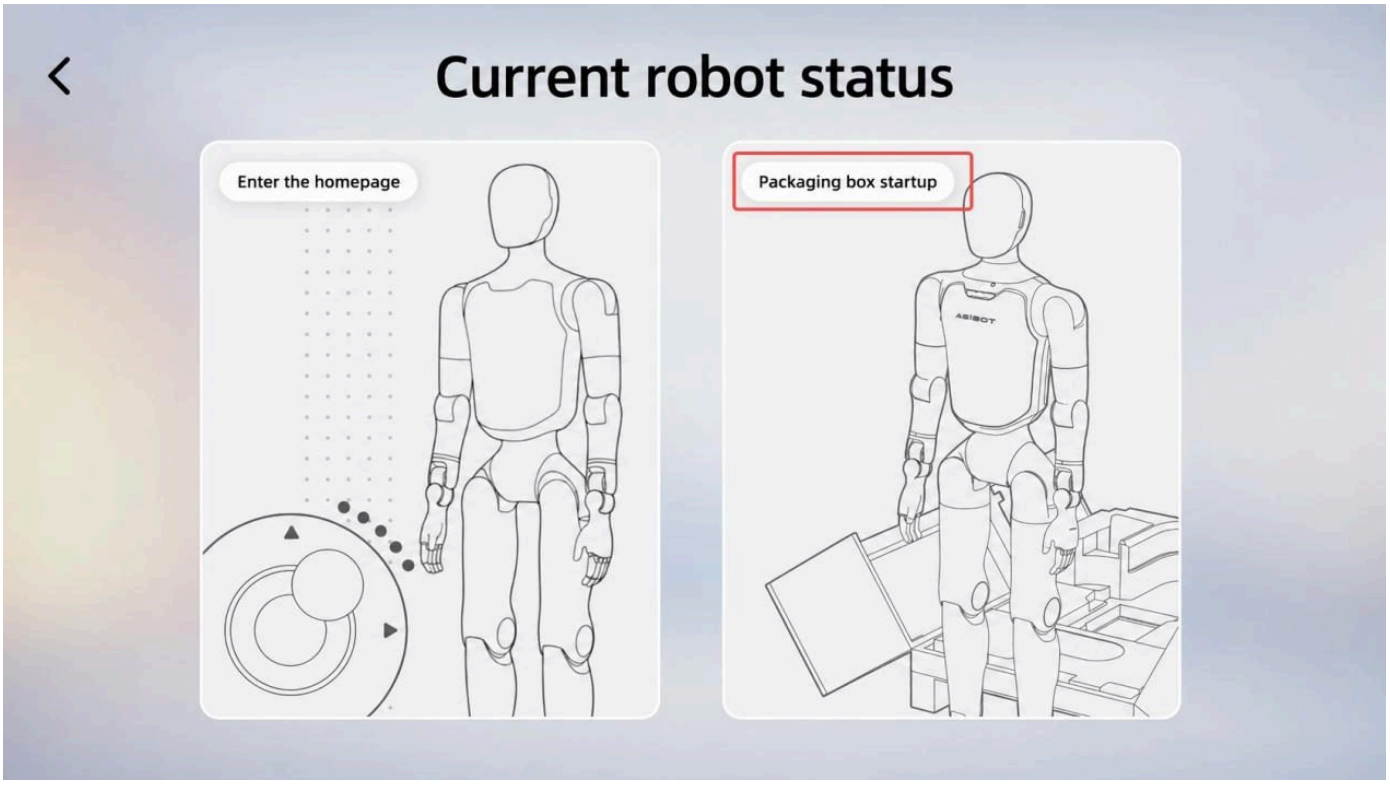
Step 3: Power on and start

Press and hold the robot's power button to turn on the robot. After the robot is powered on, the head screen and the indicator light on the chest will light up.



Step 4: Connect to AimMaster

Complete the connection between AimMaster and the robot according to the steps in Section 4.1, and select the Packing Box startup option on the robot status page

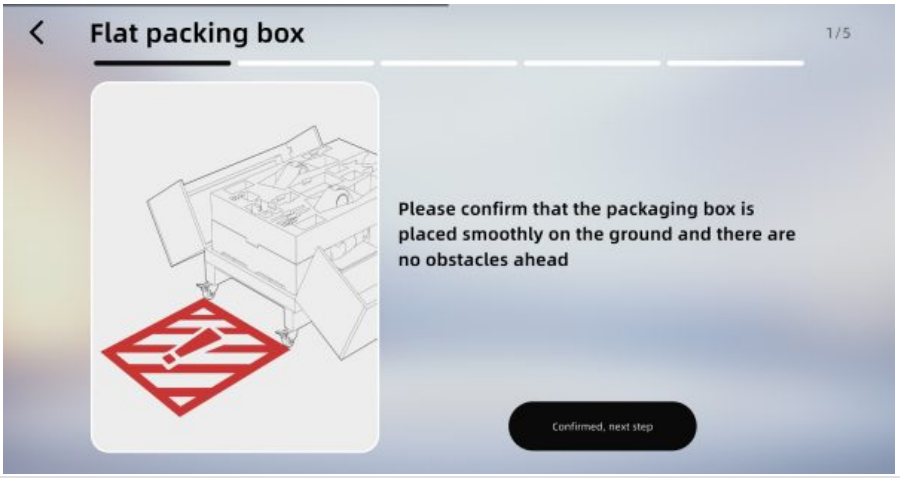


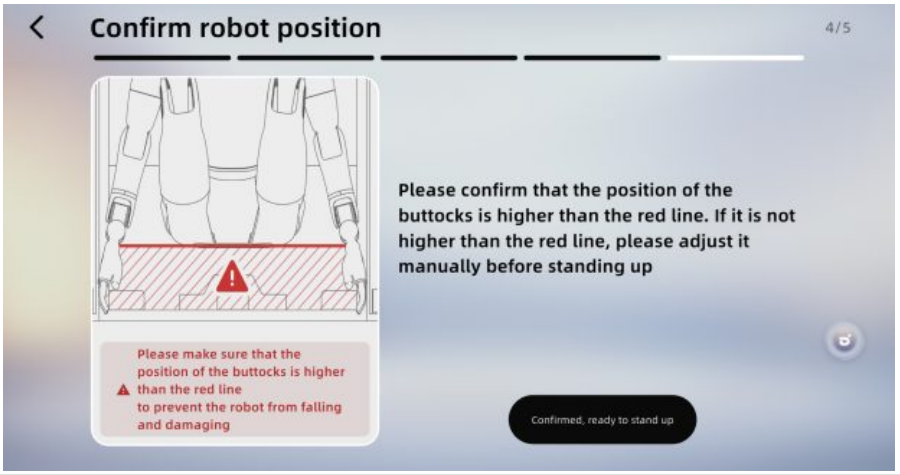
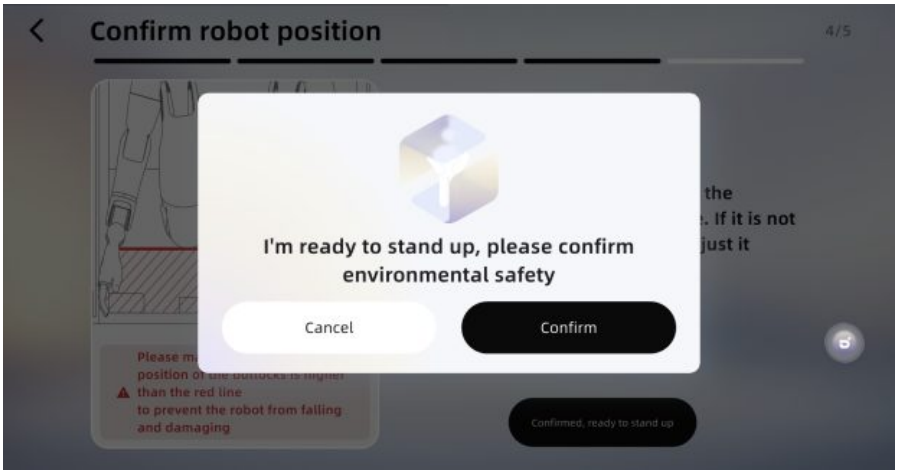
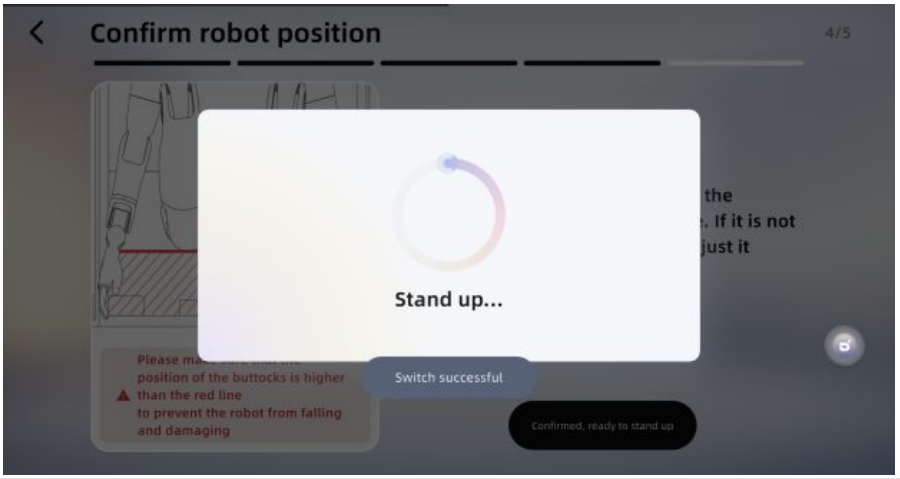
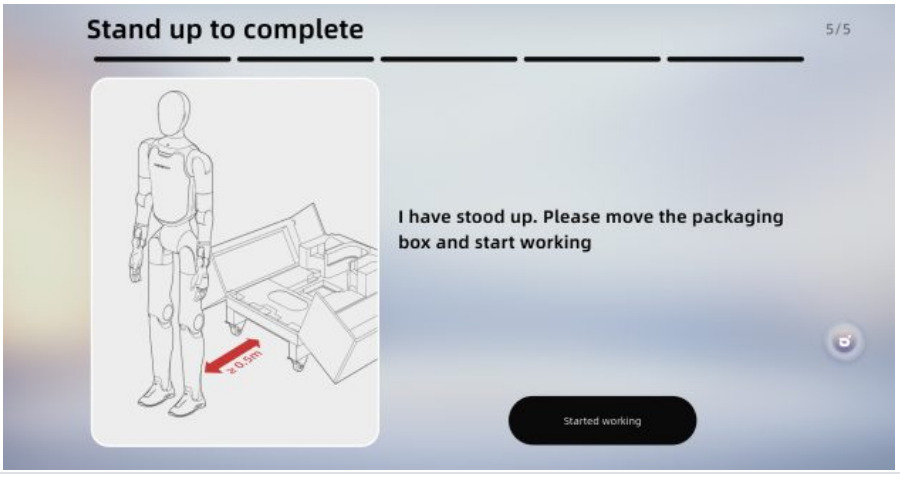
Step 5: Stand up inside the box

After confirming the environment step by step in AimMaster, control the robot to stand up from the box with one click. The robot will then enter the motion state and maintain a stable standing posture.

Note:
- Ensure no obstacles are present in front of the packaging box.
- Lock all casters of the box securely.
- Make sure the robot's hip position is above the red line; adjust it manually if not.

• After the robot stands up, move the packaging box at least 0.5 meters away before operation.

Operation Steps	Operation Interface
Ensure the packaging box is placed steadily with no obstacles ahead	
Confirm the box casters are locked	
Confirm the middle layer and hip-cover foam is removed	

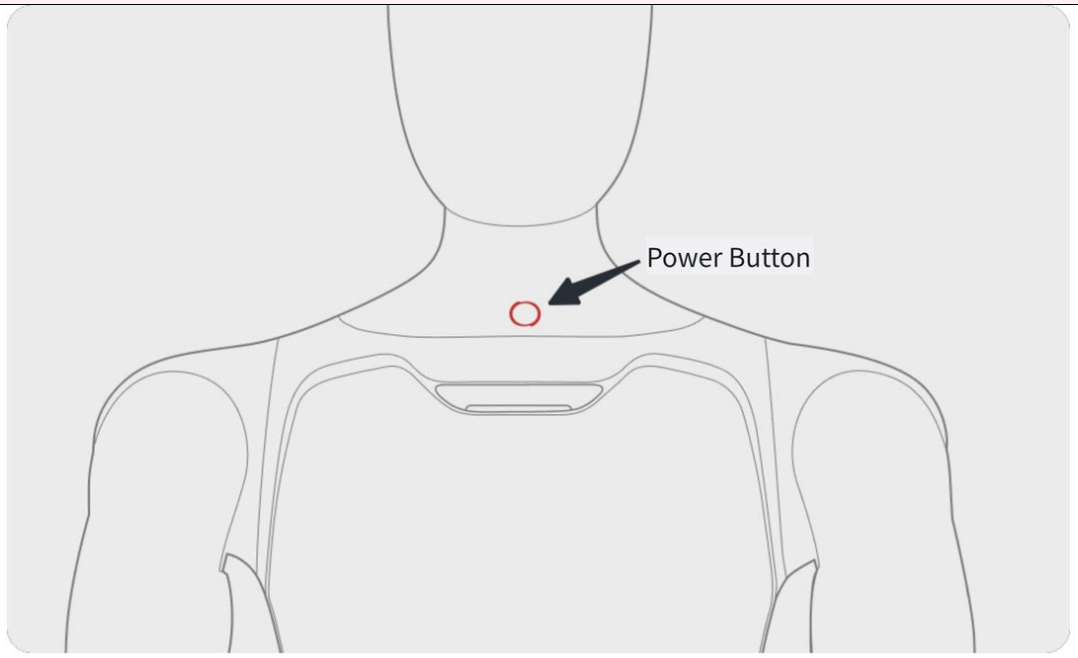
Confirm that the robot's position is correct	
Confirm initiating the robot stand-up	
Robot standing up (automatic)	
The robot successfully stands up, moves the packing box away, and ready to use	

4.2.2 **Power On in Supine Position**

Step 1: Power on and start

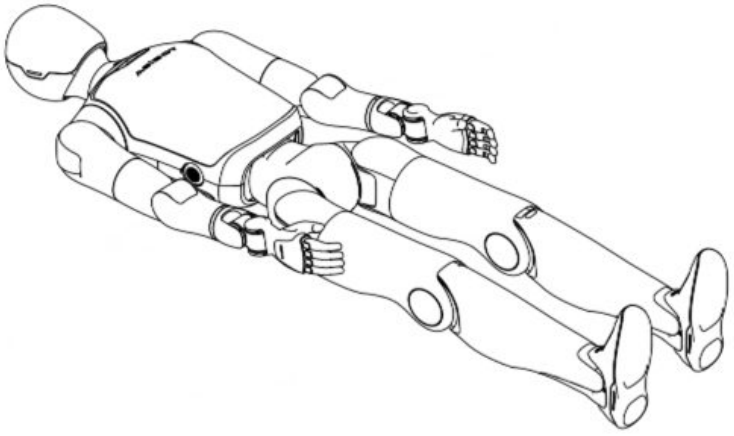
Press and hold the robot's power button to turn on the robot. After the robot is powered on, the head screen and the indicator light on the chest will light up.

> Note:
> If the battery pack is in storage and transportation mode, it is necessary to activate the battery pack before powering on. The operation method is to short press and then long press the power button on the battery pack, until all the battery pack indicator lights light up sequentially.



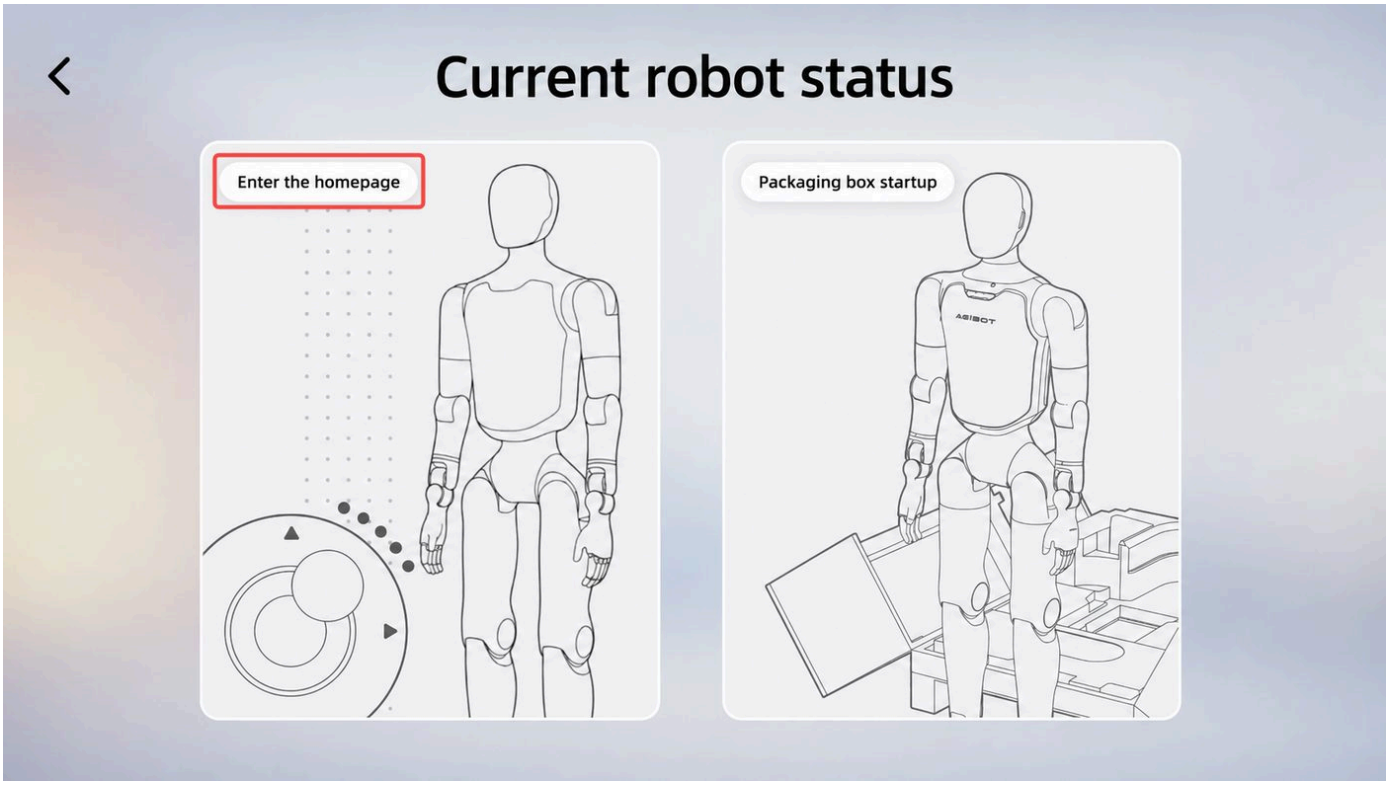
Step 2: Lay the robot flat

Lay down the robot on a flat surface as shown in the following illustration, ensuring that the entire body of the robot faces upward, its limbs are extended, and its arms are naturally placed on both sides of the body.



Step 3: Connect to AimMaster

Complete the connection between AimMaster and the robot according to the steps in Section 4.1, and select the homepage entering option on the robot status page.

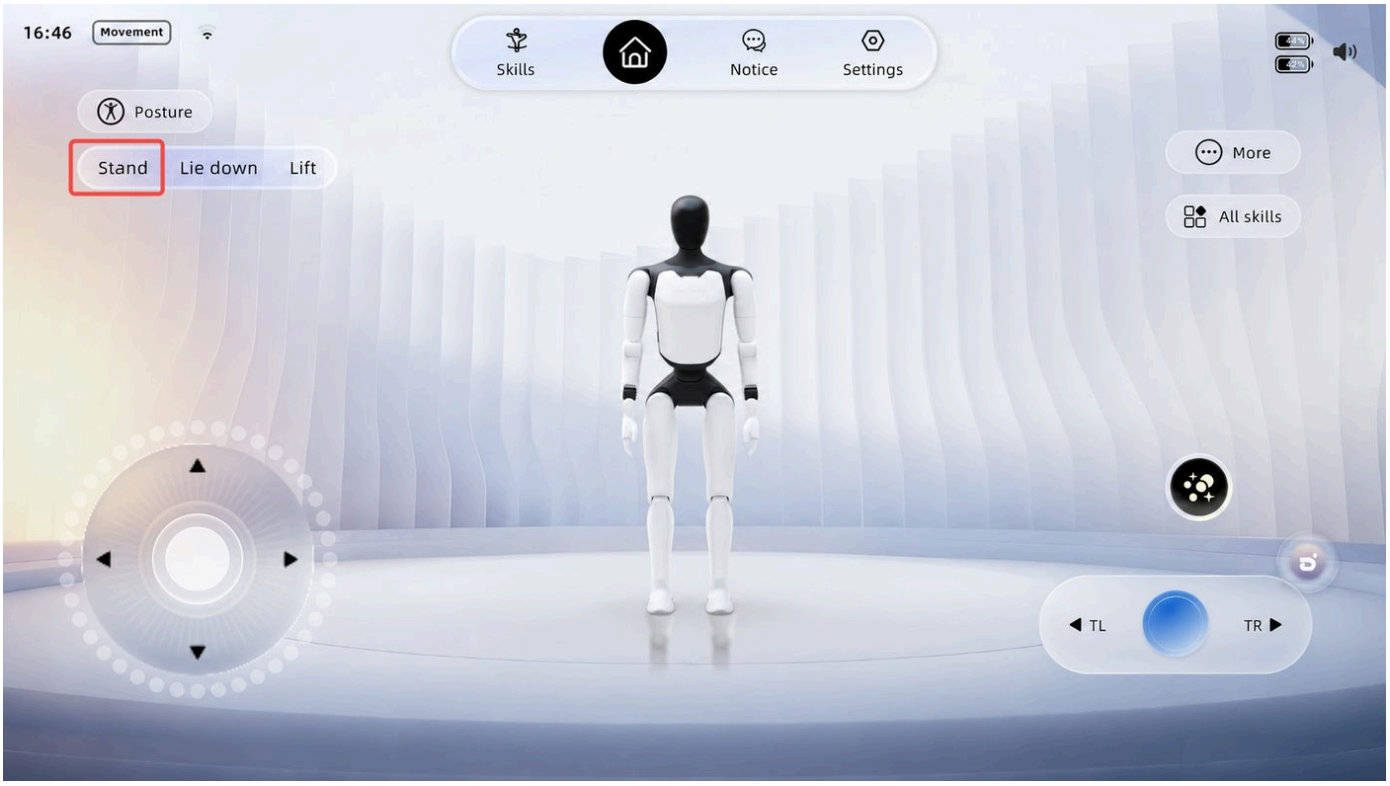


Step 4: Confirm environmental safety

Before triggering the lying-down-to-standing-up action, it is necessary to ensure that there are no foreign objects within a 1-meter radius around the robot to reserve sufficient safety space for the action execution.

Step 5: Stand up from lying flat

Under the Posture switch on the home page of AimMaster, choose "Stand" to enable the robot to stand up from a lying position. At this time, the robot enters a motion state and stands stably.

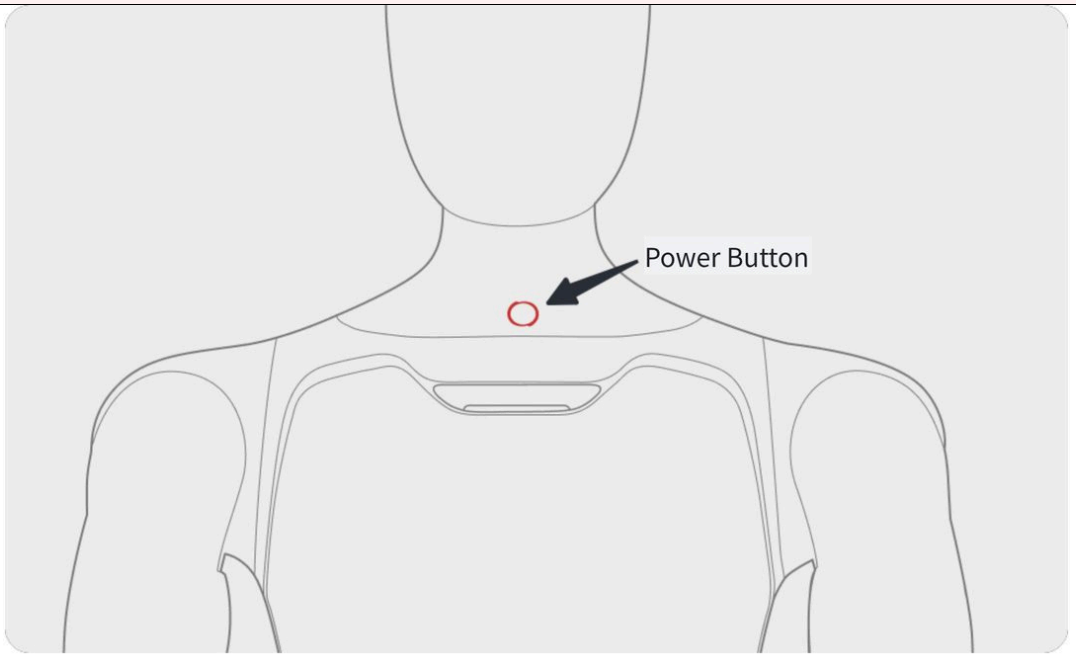


4.2.3 Power On in Prone Position

Step 1: Power on and start

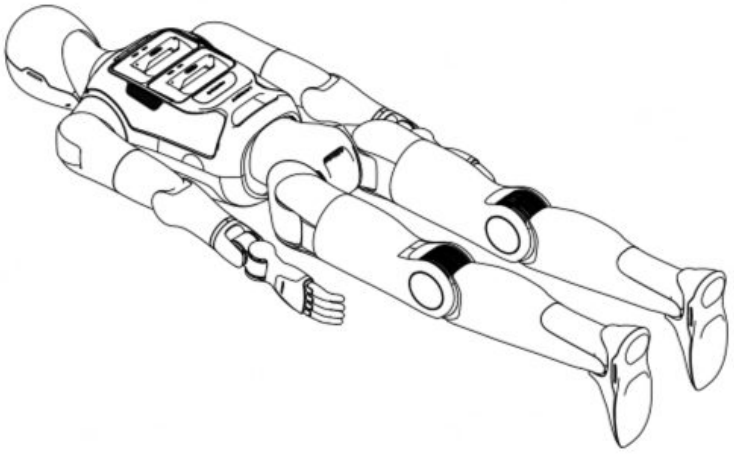
Press and hold the robot's power button to turn on the robot. After the robot is powered on, the head screen and the indicator light on the chest will light up.

> Note:
> If the battery pack is in storage and transportation mode, it is necessary to activate the battery pack before powering on. The operation method is to short press and then long press the power button on the battery pack, until all the battery pack indicator lights light up sequentially.



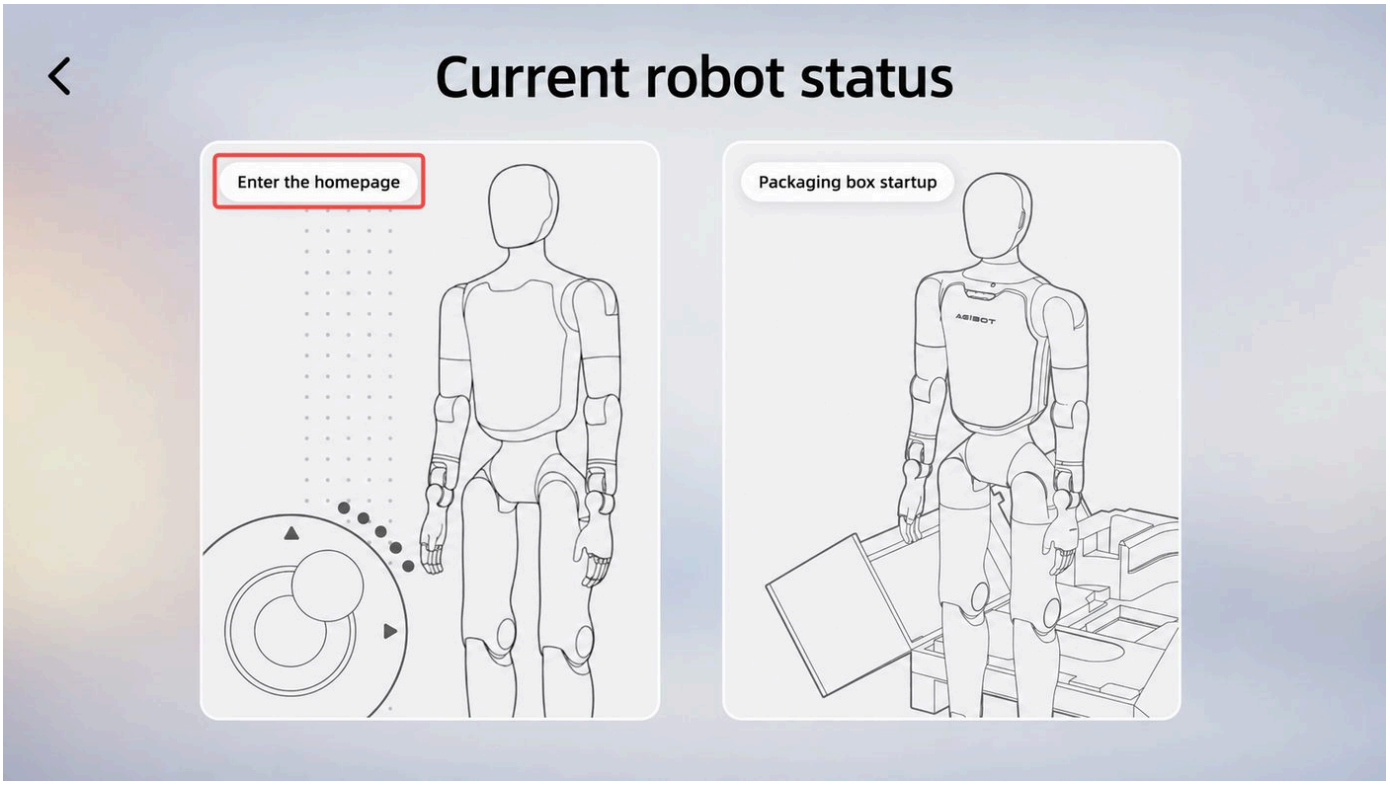
Step 2: Lay the robot face-down

Lay the robot face-down on a flat surface as shown in the illustration, ensuring that the entire body of the robot faces downward, its limbs are extended, and its arms are naturally positioned on both sides of the body.



Step 3: Connect to AimMaster

Complete the connection between AimMaster and the robot according to the steps in Section 4.1, and select the homepage entering option on the robot status page.

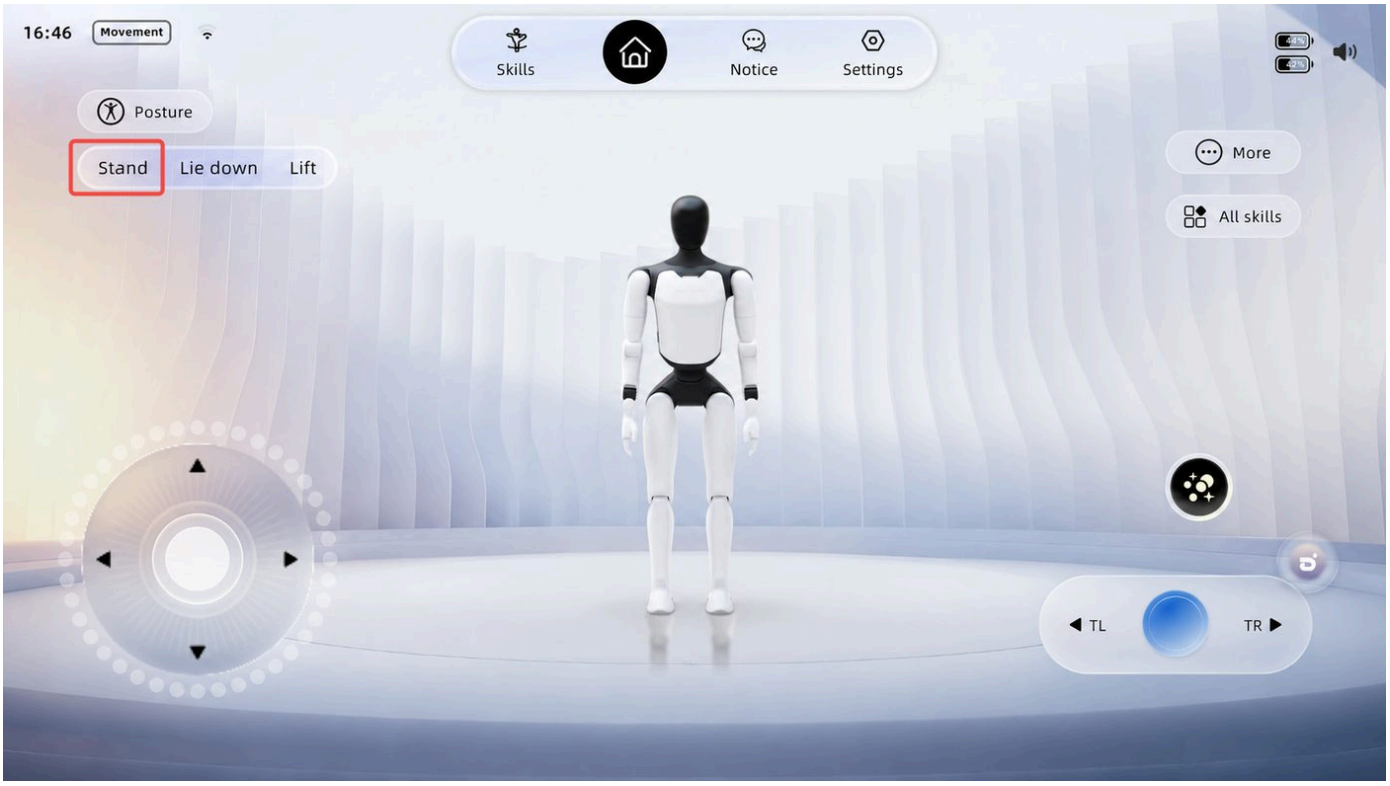


Step 4: Confirm environmental safety

Before triggering the prone-to-standing action, it is necessary to ensure that there are no foreign objects within a 1-meter radius around the robot to reserve sufficient safety space for the action execution.

Step 5: Stand up from a prone position

Under the Posture switch on the home page of AimMaster, choose "Stand" to enable the robot to stand up from a lying position. At this time, the robot enters a motion state and stands stably.



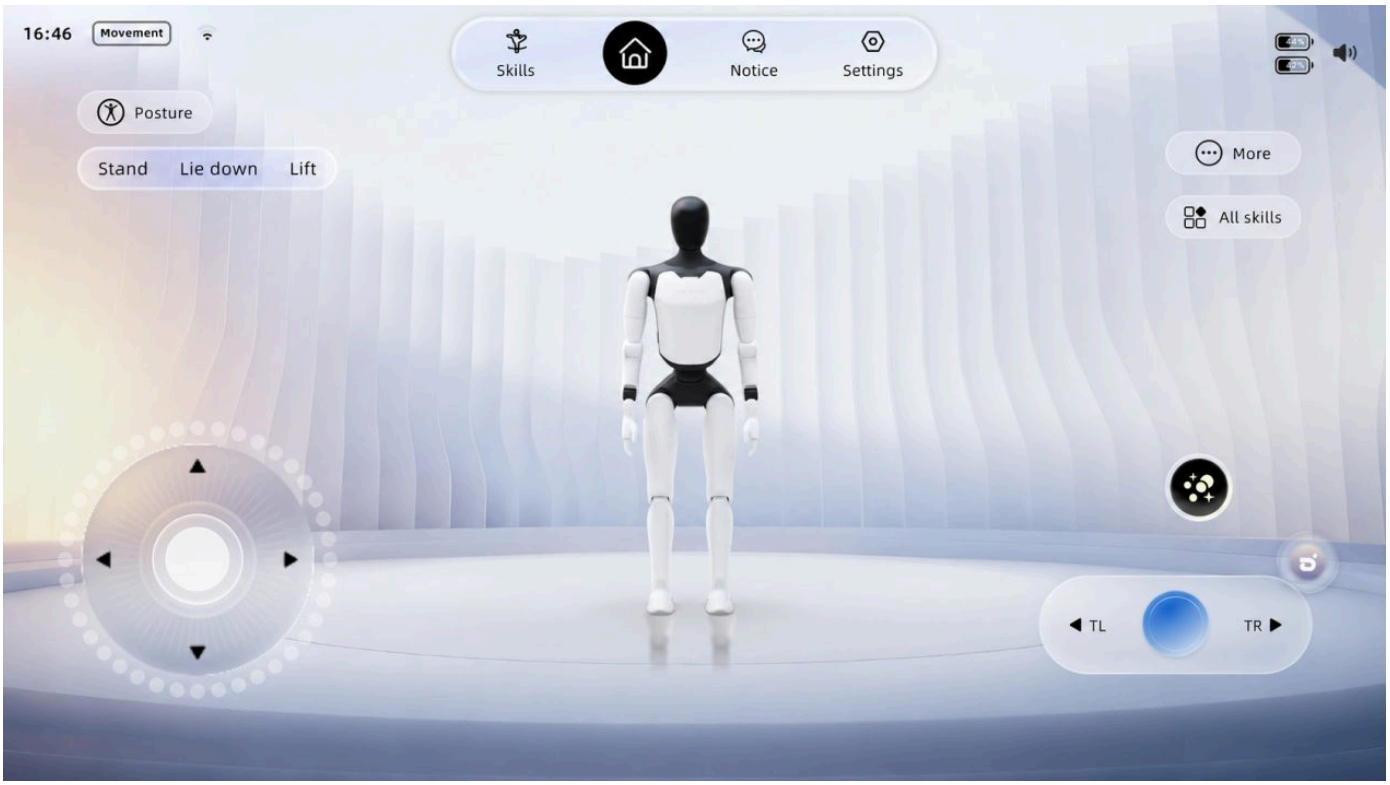
4.3 Shutdown Process

4.3.1 Shutdown and Packing

Note:

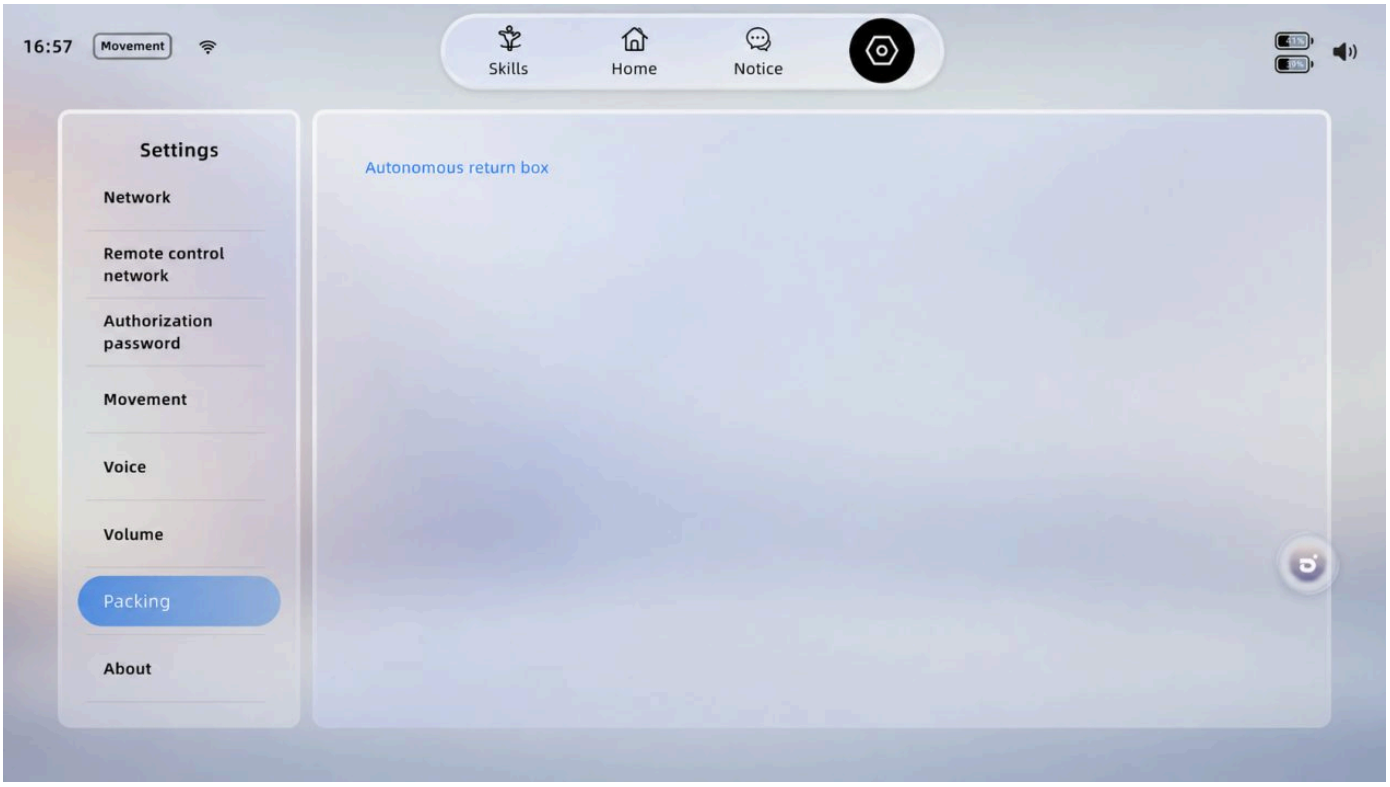
- When moving the packing box to align with the robot, be sure not to hit the robot;
- Before the robot enters the packaging, confirm that all casters have been locked.

Step 1: The robot is in motion and standing stably



Step 2: Initiate the self-service return process

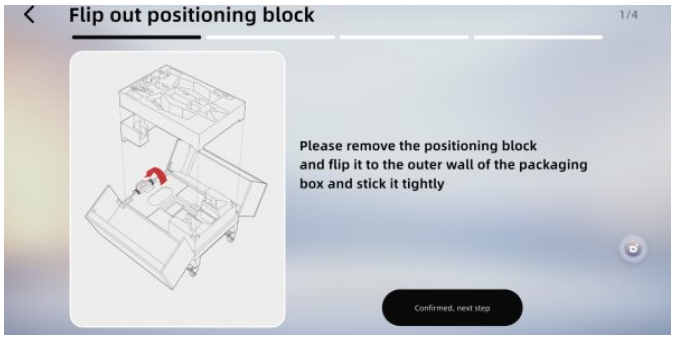
On the-page of AimMaster, choose, and start the return-to-box process after ensuring the surface is level.



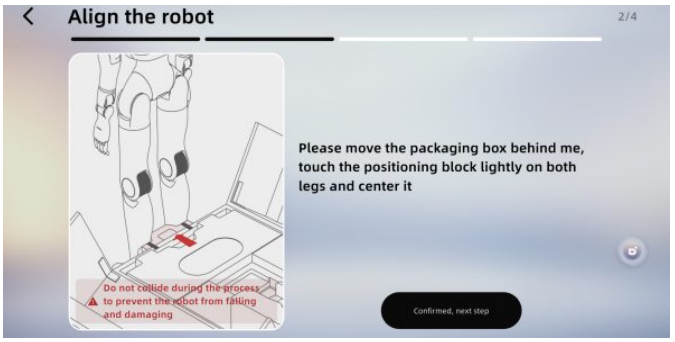
Step 3: Move and position the packaging box

Pull out the positioning block from inside the packing box, turn it over to the outer wall of the packing box and press it firmly against the wall; move the packing box to the back of the robot so that the positioning block gently touches both legs and centers itself for positioning.

Step 3-1: Flip out the positioning block



Step3-2: Align the robot



Step 4: Lock the packing box

Lock all the casters of the packing box, and confirm that the inside of the packing box has been cleaned up.



Step 5: Robot returns to the box

After confirming environmental safety, confirm to start entering the packaging box.

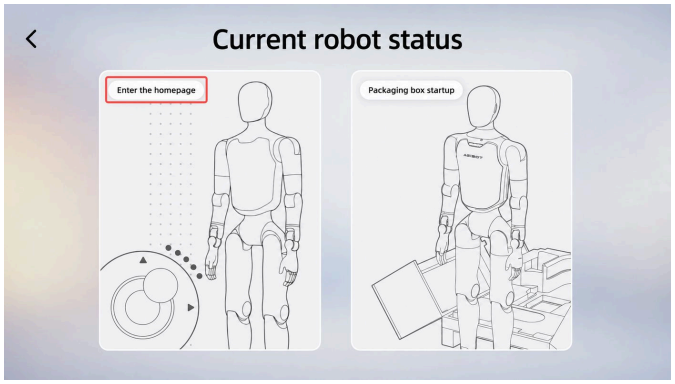
Step 6: Shut down and pack

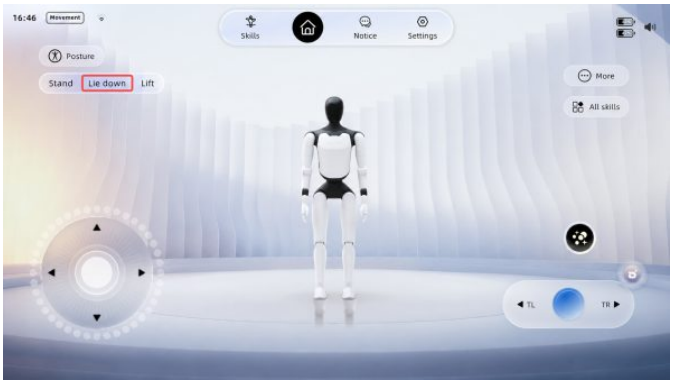
After the robot is placed inside the packaging box, briefly press the power button on the chest, and follow the voice prompts to turn it off; then insert the positioning block, hip-cover foam, and middle layer foam back into their original positions to secure and protect the robot; finally, close the packaging box and lock it.

4.3.2 Shutdown with Supine Position

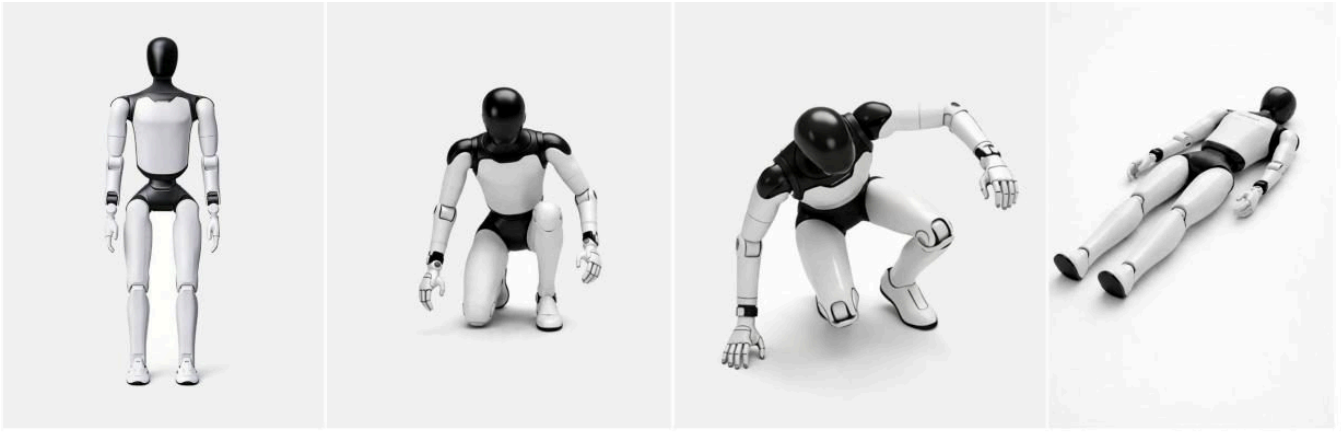
Caution: Ensure a 1-meter radius safety space around the robot to avoid collisions.

Step 1: The robot is in motion mode, use the **remote control to connect to the robot**





Step 2: Remote control the robot to lie flat



Step 3: Short press the power button on the chest, and follow the voice prompts to turn off the device

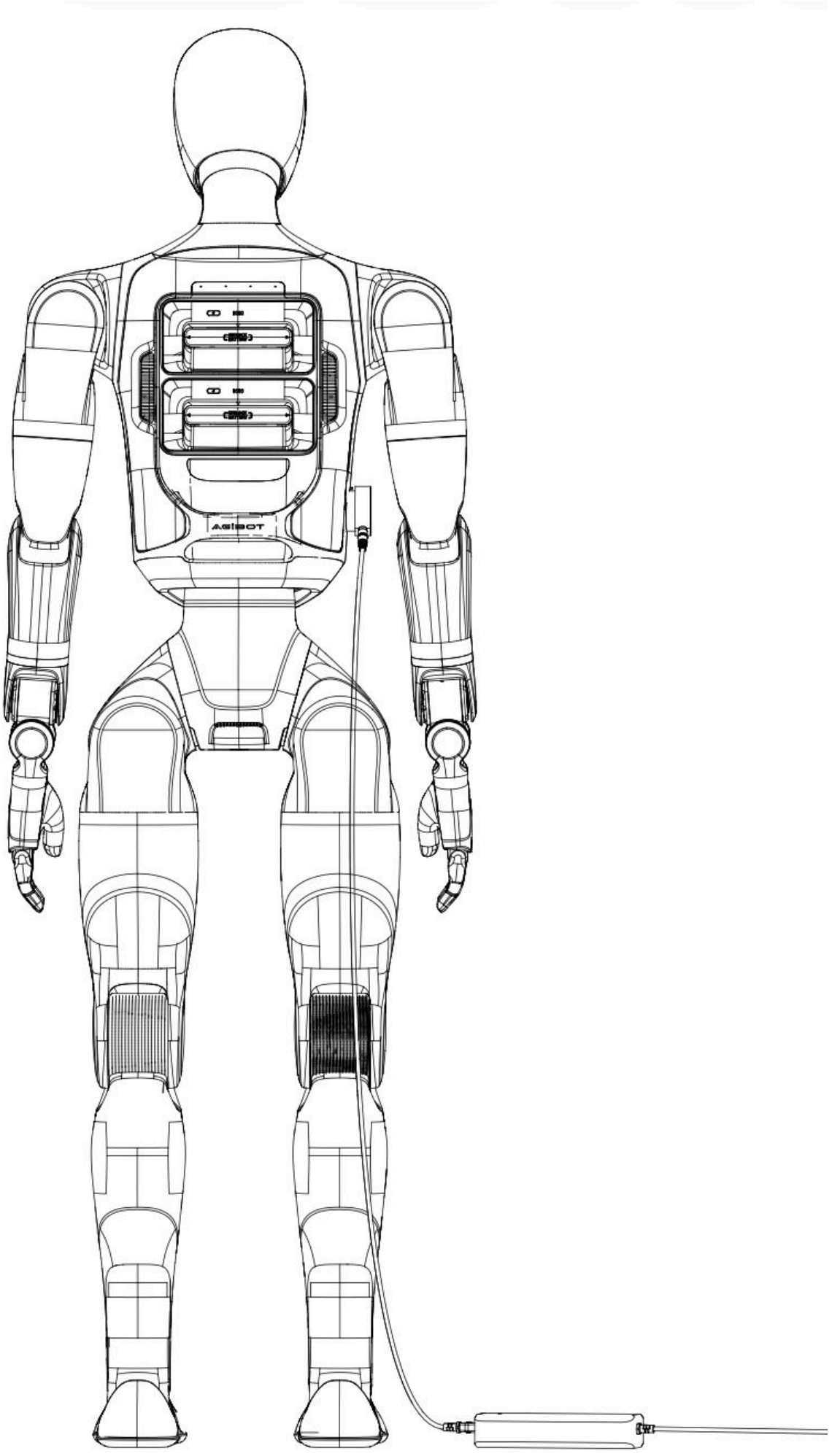


4.4 Charging and Battery Changing

4.4.1 Charging Mode

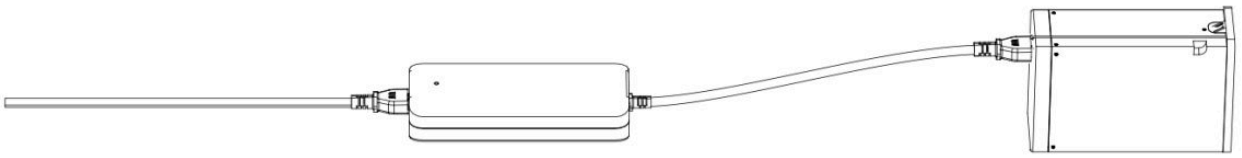
1. Charging the robot with battery installed

When both batteries are in place, the magnetic charging head of the charger can be connected to the charging port of the robot. After the power is turned on, the magnetic charging head of the charger lights up green, indicating successful charging. The schematic diagram is as follows:


AGIBOT

2. Charging the battery solely

Remove the battery and separate the magnetic adapter section of the charger to directly charge the battery. The schematic diagram is as follows:



4.4.2 Battery Changing Mode

> Note:
> If the battery pack is in storage and transportation mode, it is necessary to activate the battery pack before powering on. The operation method is to short press and then long press the battery pack power button until all the battery pack indicator lights light up sequentially.

Step 1: Remove an individual battery

Step 2: Insert the "new" battery

Step 3: Repeat the above actions and replace the second battery

* Individual battery can be removed in both the shutdown state and the powered-on standing state (when only a single battery is left in place, the robot is restricted from moving)

> Note:
> If the battery pack is in storage and transportation mode, it is necessary to activate the battery pack before powering on. The operation method is to short press and then long press the battery pack power button until all the battery pack indicator lights light up sequentially.

4.5 Emergency Stop Function

The emergency stop function is used for the emergency stop of the robot in case of sudden situations, preventing further damage to the robot or the surrounding environment, and can be triggered in the "software emergency stop" mode.

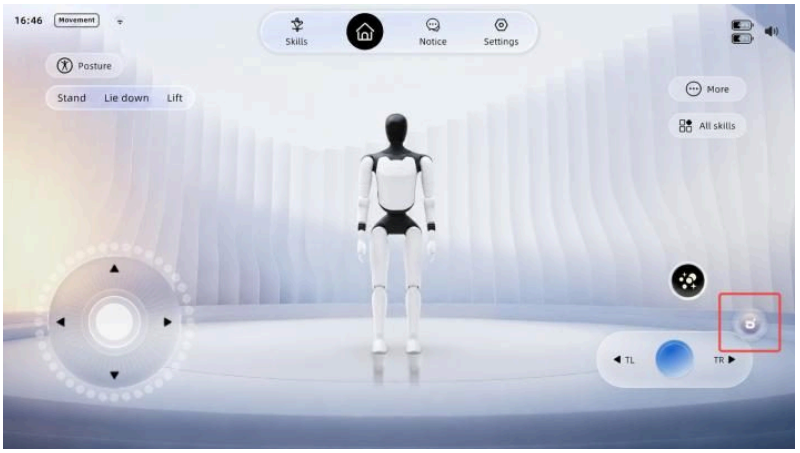
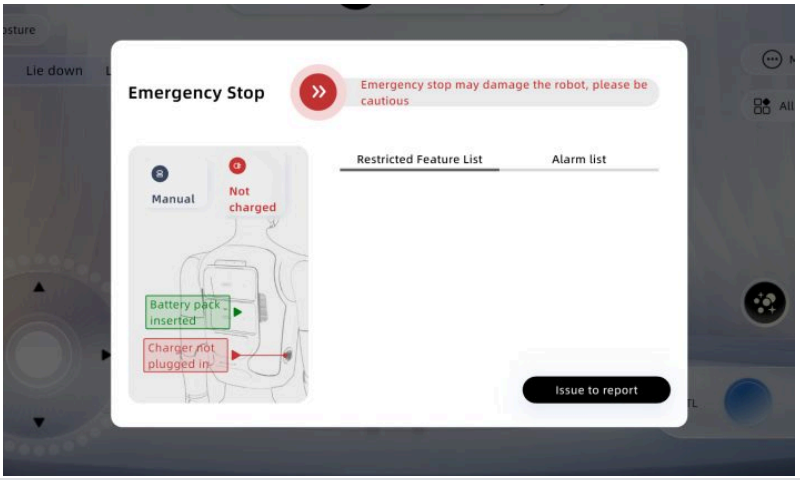
After the robot enters the emergency stop state, its limbs will lose power and fall to the ground, with a certain risk of damaging the machine. Please ensure that users use the emergency stop function with extreme caution.

4.5.1 Soft Emergency Stop

1. Steps to trigger the emergency stop state

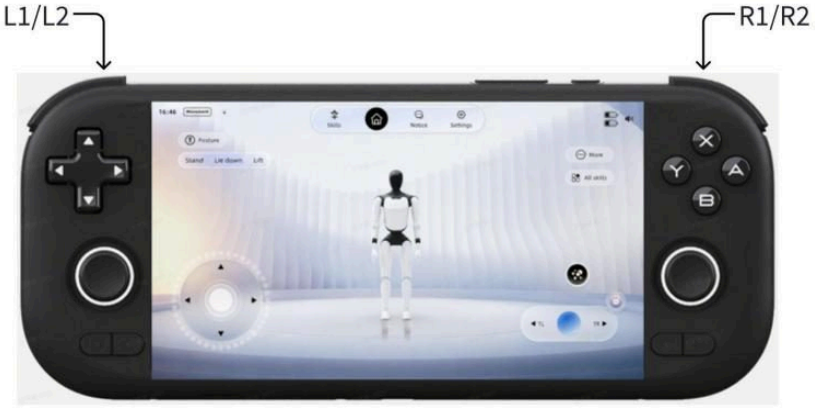
- Method 1: Triggered via AimMaster

Operation Steps	Operation Interface

Press the floating ball to enter the emergency stop page	
Press and hold the [Emergency Stop] button, then slide it to the right until it reaches the end to trigger a soft emergency stop	
Enter the soft emergency stop state	

- Method 2: Triggered by remote control buttons (applicable to remote controls)

  When the remote control is connected to the robot, hold the four buttons **L1+L2+R1+R2 at the same time for more than 0.5 seconds** to trigger the soft emergency stop state.

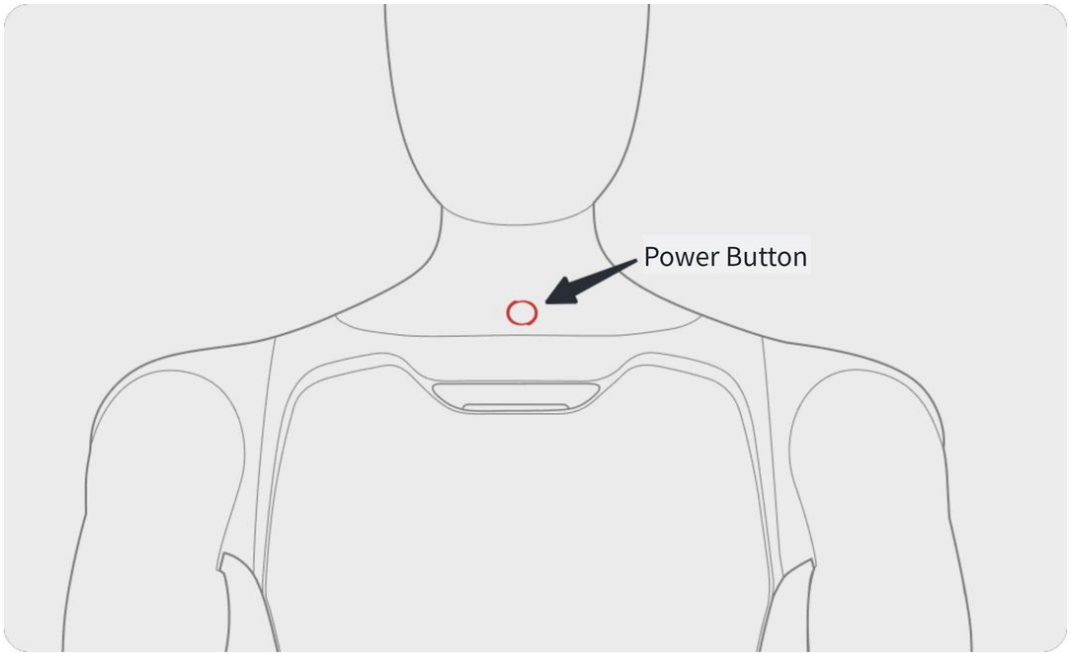


2. Operable items in the soft emergency stop state

After the robot enters the soft emergency stop state, only limited operations such as viewing the function list, alarm information, and reporting problems can be performed on the Enmergency Stop page.

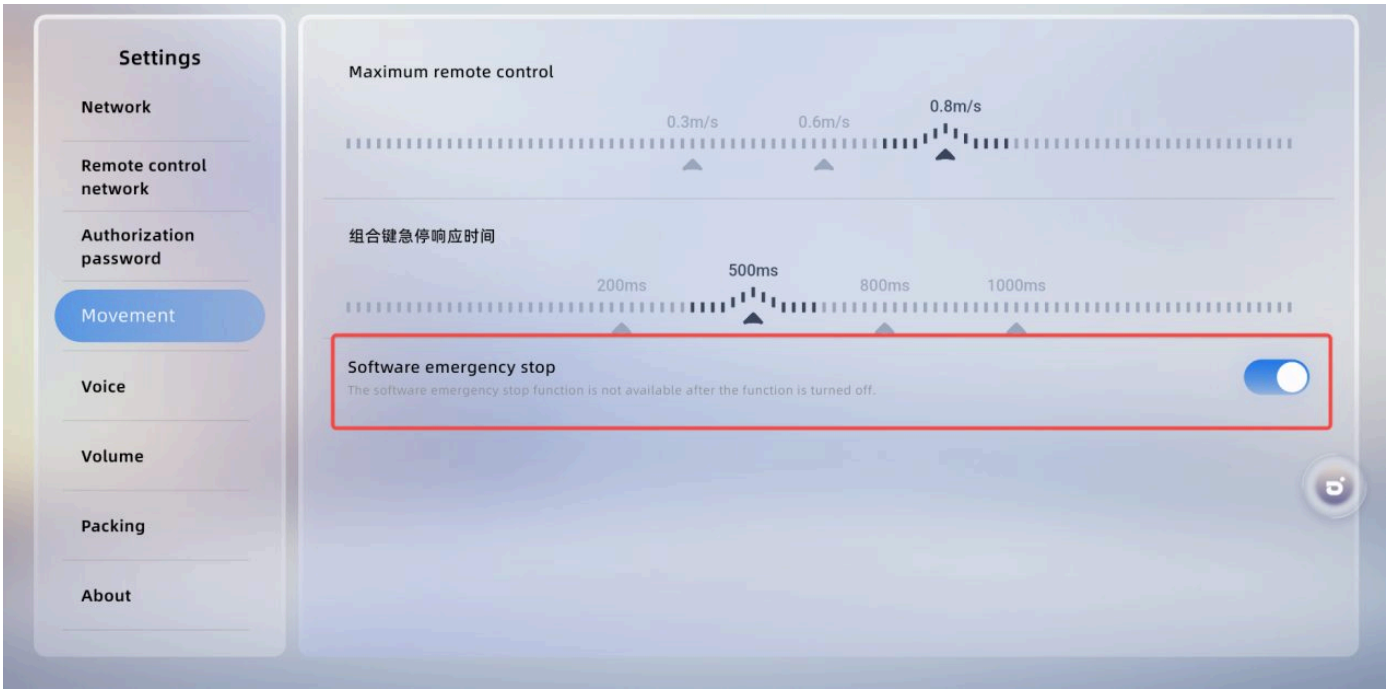
3. Steps to Exit the Soft Emergency Stop State

Restarting the robot to exit the soft emergency stop state



4.5.2 Emergency Stop Settings

Turn on/off the soft emergency stop function: On the [Settings] - [Movement] page of AimMaster, you can turn on and off the software emergency stop function.



4.6 Replace silicone hand

4.6.1 Remove Silicone Hands (use screwdriver in the accessory kit)

Step 1: Remove the silicone strip above the robot's hand to expose the screws

Before removal:



After removal:



Step 2: Remove the four screws (two in the front and two in the back) that secure the hand

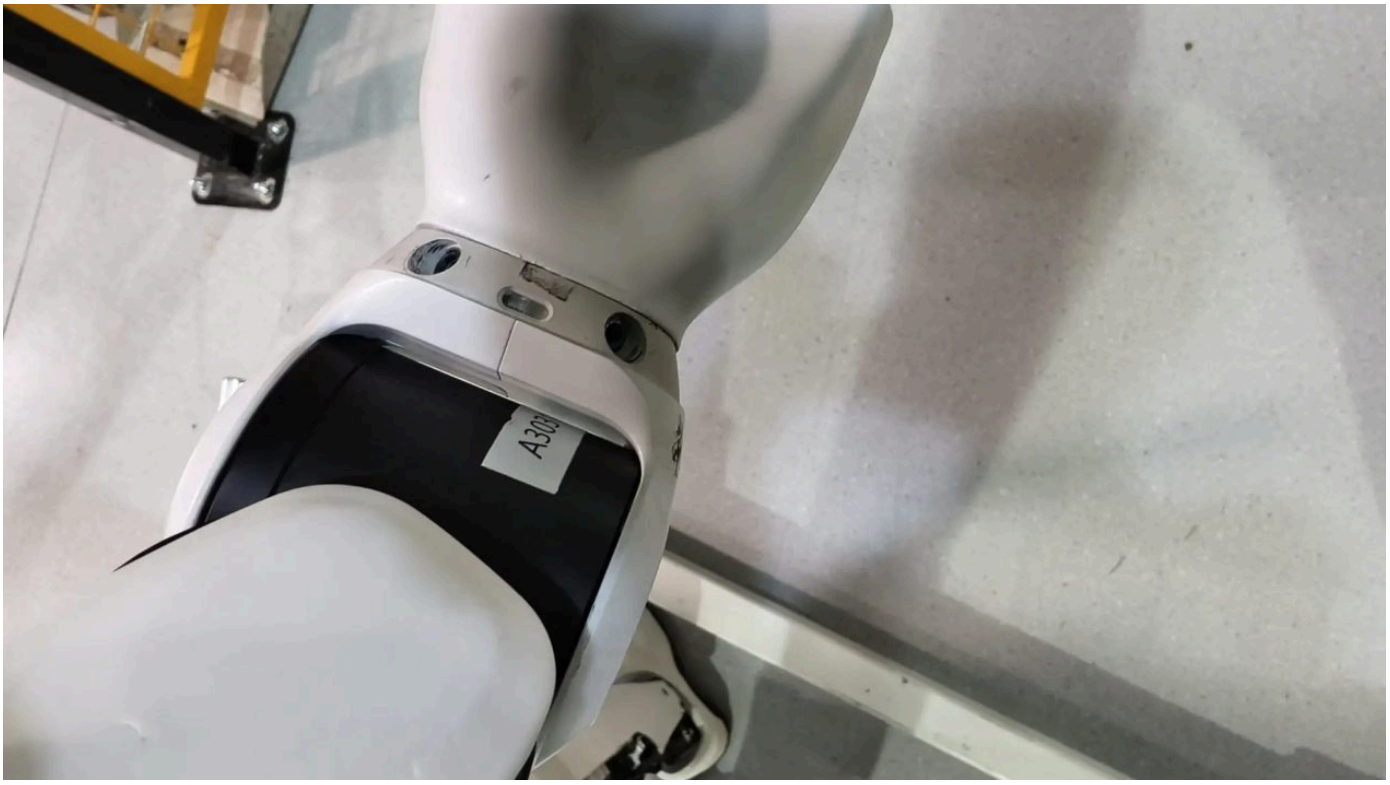


After removal, the hand can be detached (as shown in the figure)

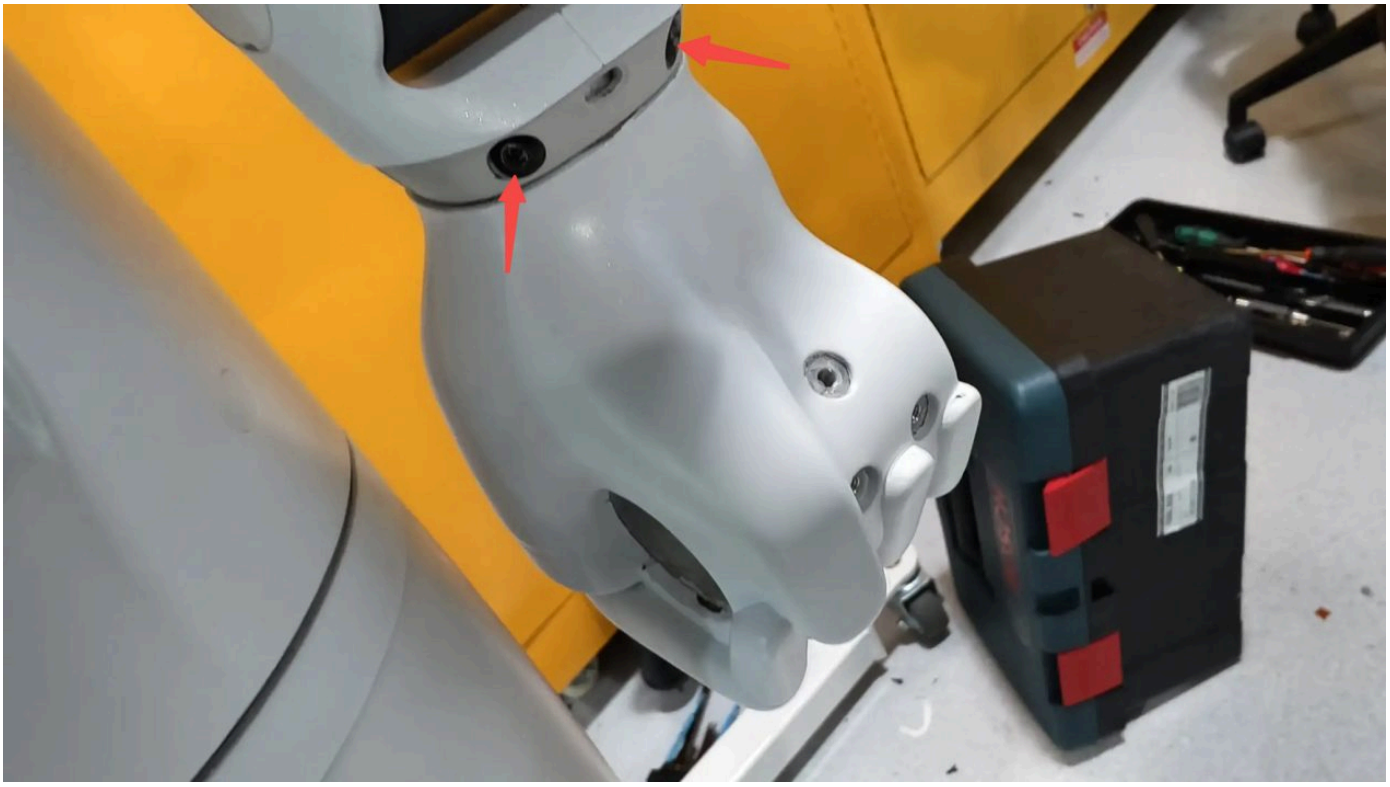


4.6.2 **Install Silicone Hands**

Step 1: Align the silicone hand with the forearm and join them together



Step 2: Install a total of four screws, front and rear



Step 3: Place the silicone strip according to the position to cover the four screws

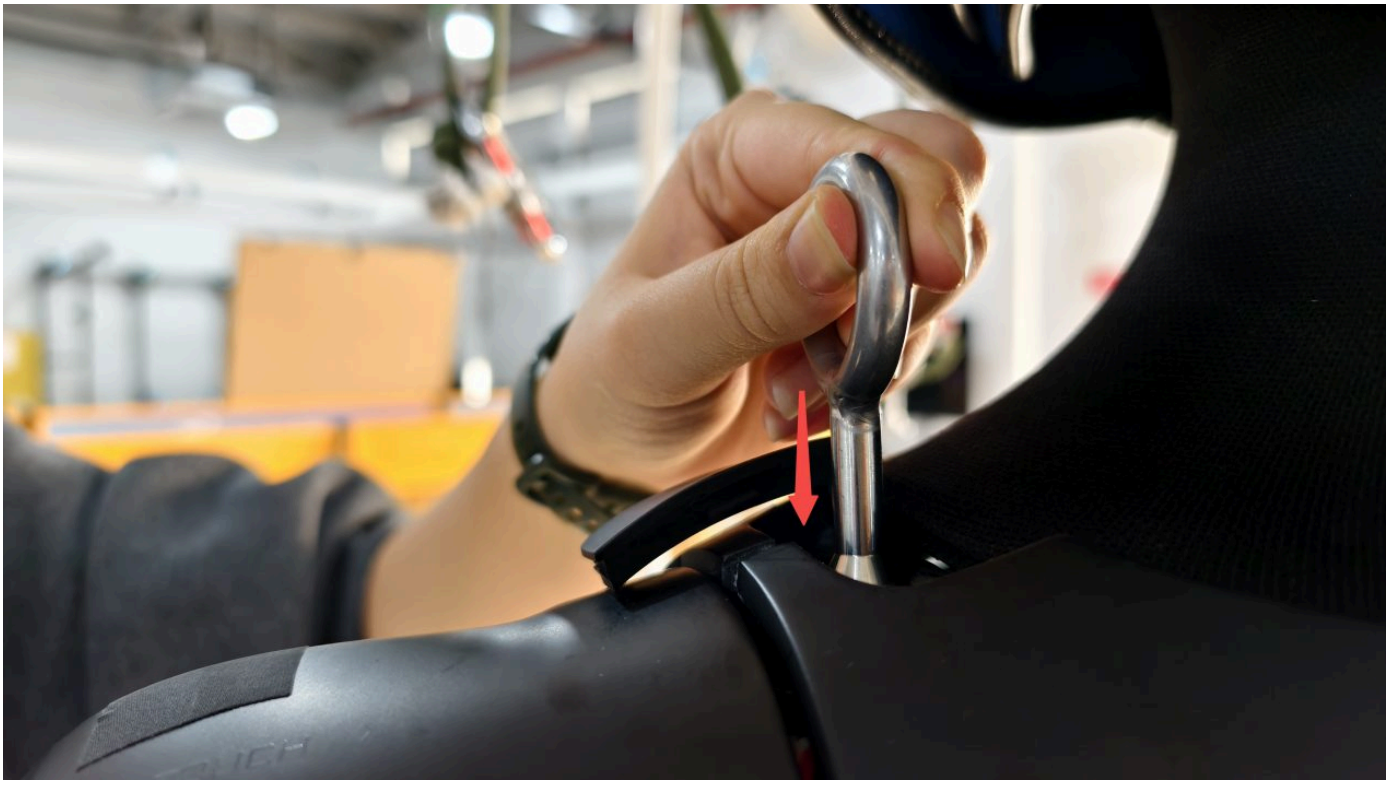


4.7 Lifting Ring Installation

• **Step 1:** Pull out the rubber plugs on both shoulders of the robot to expose the mounting slot



• **Step 2:** Hold the ring end and align the buckle end with the slot and press it firmly



• **Step 3:** Rotate the lifting ring 90° and leave it there

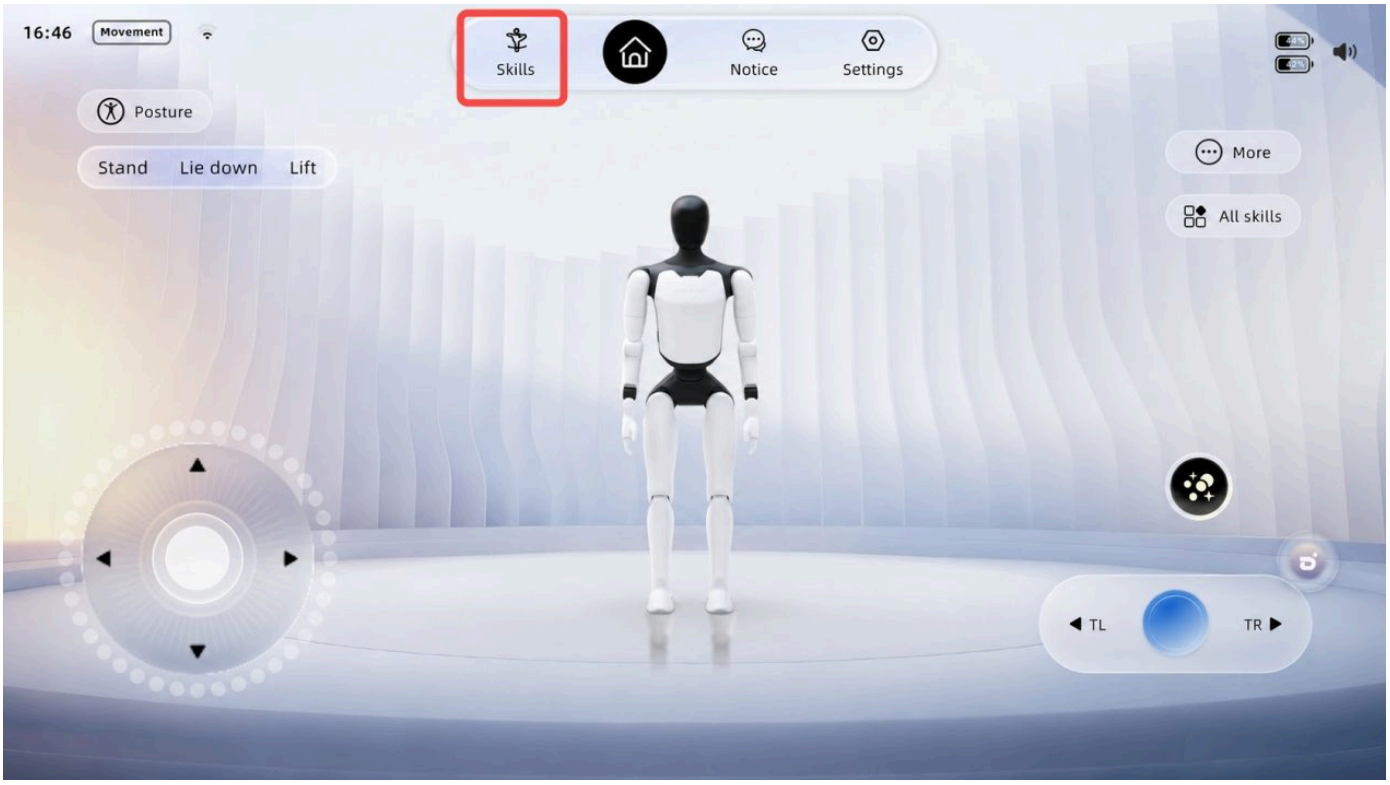


5. Function Description

5.1 Full-body Dance

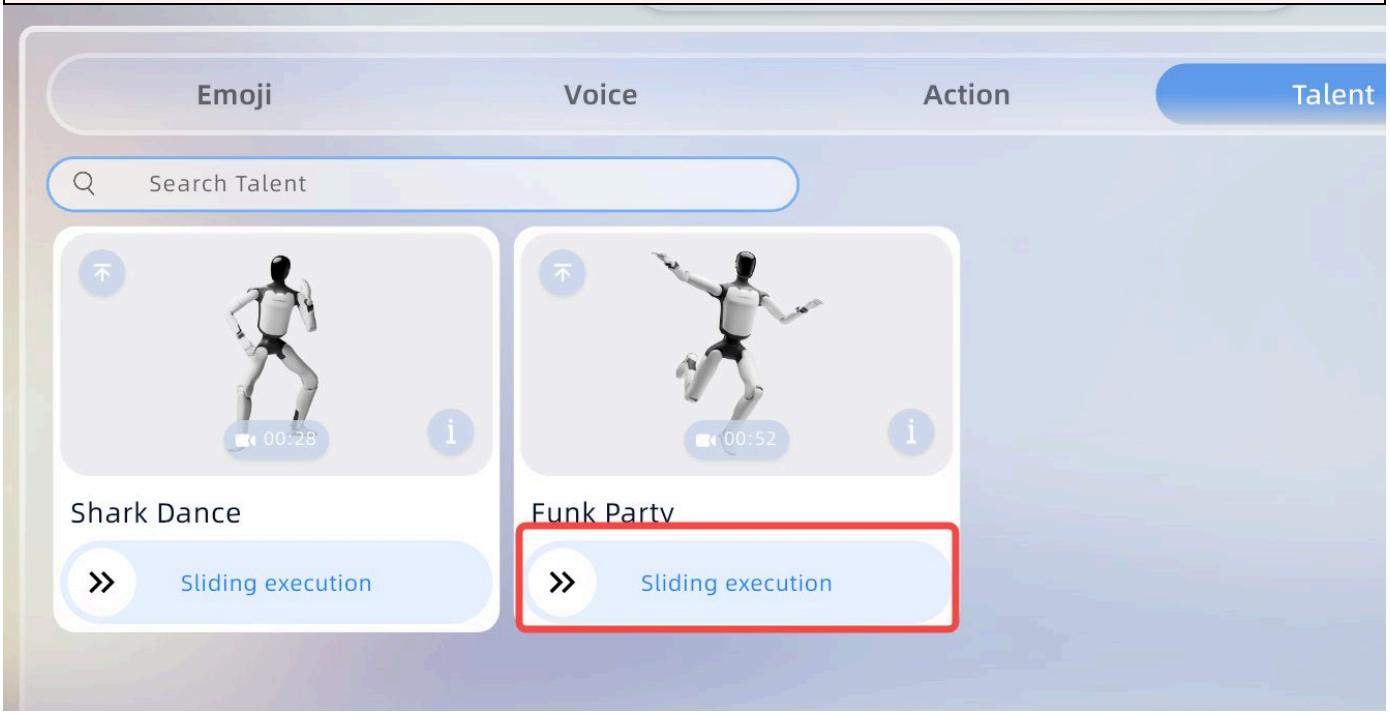
Select the dance content from the skill set and slide to play

Step 1: Press the [Skills] the top tab bar



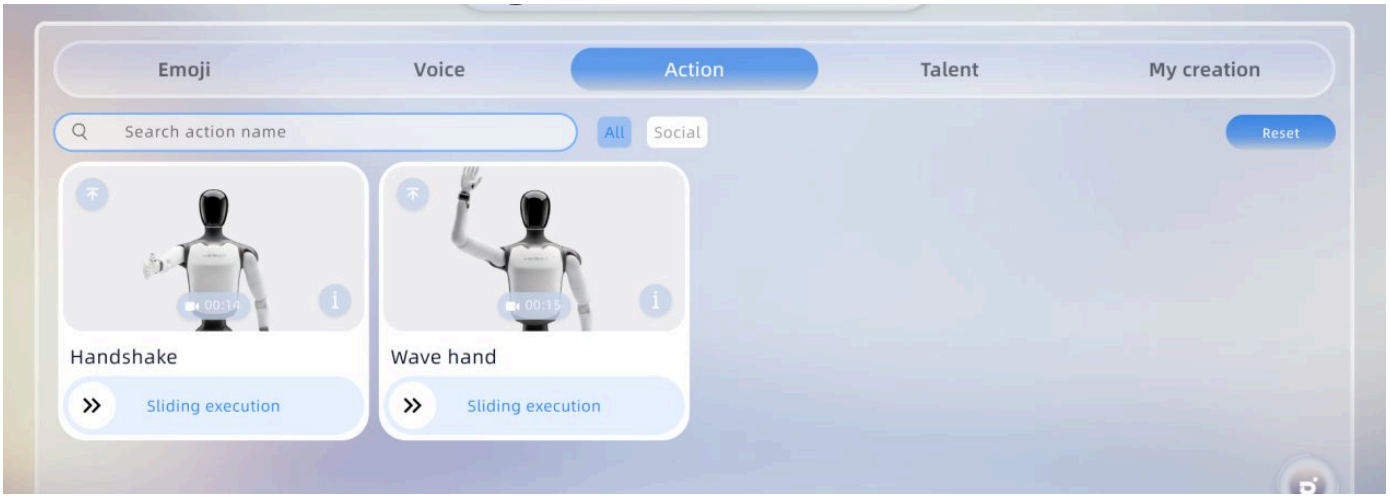
Step 2: Select the desired dance, and slide to execute

Note: Dances need to be confirmed and executed according to pop-up instructions. Follow the tips to ensure safety.



5.2 **Body Actions**

From the skill set the user can select different actions to play.



5.3 **Robot Interaction**

1. The robot is equipped with two voice interaction inputs: **Built-in Mic** and **External Mic**, which can be switched in the voice settings on AimMaster.
2. Actions and dances can be triggered by voice commands, such as “Please shake hands” and “Give me a dance. The user needs to **set up the voice interaction language on LinkSoal Platform** before use voice commands.
3. Adopts a new abstract geometric expression system with dedicated designs for power-on, idle, wake-up, listening, speaking, working, and dancing states.
4. Additional features will be added in subsequent OTA updates. For details, refer to the release notes of each version.

5.4 **LinkSoul Platform**

LinkSoul Platform is a robot personality customization platform launched by AGIBOT for both enterprise and individual users. It allows you to endow the robot with unique personality and characteristics through simple and intuitive operations.

- **Individual Users**: Can fully customize the robot’s interactive experience, including character design, personality, voice tone, knowledge base, skills, facial expressions and memory. Users can create a unique “persona” on the platform and bind it to the robot to realize an immersive interactive experience.
- **Enterprise Users**: Can use scenario-specific intelligent agent templates (e.g., exhibition guide, healthcare companion, shopping assistant, front desk receptionist) to quickly deploy robots into business scenarios for efficient implementation and intelligent upgrading.

Detailed Usage Documentation for LinkSoul Platform:

 LinkSoul User Manual

Official website of LinkSoul Platform:

Asia: https://linksoul-sg.agibot.com/

EU: https://linksoul-eu.agibot.com/

America: https://linksoul-us-east.agibot.com/

6. Accessories Management and Usage

6.1 4G/5G Module User Guide

Robots are equipped with built-in eSIM cards. For details on the specific installation and warranty services, please refer to Section 8.1 of this article.

6.1.1 SIM Card Specifications

The A3 supports Micro-SIM cards for internet access. Its cellular communication module is compatible with 4G/5G protocols. **Actual network availability may vary by service provider**. Please refer to your sales contact for inquiries about SIM Card support.

6.1.2 SIM Card Installation

On the neck of the device, the SIM card slot can be seen by removing the black silicone protective cover.



7. **Daily Maintenance and Management**

Compliance with the above instructions ensures safe and efficient operation of the robot. For any inquiries, please contact the manufacturer or authorized service provider for technical support.

Safety Warnings

1. Power-off Maintenance: Before any maintenance or component replacement, **completely power off the device** and confirm it is in a fully de-energized safe state.
2. No Unauthorized Modification: Do not modify the robot or alter its original design and configuration without official authorization.
3. Professional Repair Only: Do not disassemble the robot personally. If maintenance is required, contact the manufacturer's designated professional service personnel.

Maintenance and Upkeep

1. Routine Maintenance: Perform regular maintenance in accordance with AGIBOT official recommendations to keep the robot in optimal operating condition.
2. Use Original Spare Parts: Only use manufacturer-specified original spare parts for component replacement to guarantee equipment performance and operational safety.

Fault Handling

1. Fault Response: Immediately stop operation once any malfunction occurs, and arrange for professional technicians to conduct inspection and repair.
2. No Unauthorized Disassembly & Repair: Do not disassemble or repair the robot by yourself, so as to prevent secondary damage to the device.

Battery and Power Management

1. Safe Charging: Do not disassemble the battery for separate charging; charge only by connecting the dedicated power supply.
2. Charging Environment: The robot's battery shall be charged in a safe, dry environment. Avoid humid and high-temperature surroundings.
3. Prevent Overcharging: Do not keep the device connected to power for a prolonged period to avoid battery overcharging and overheating, and to prolong battery service life.
4. Professional Battery Replacement: Battery replacement must be performed only by qualified professionals. Mismatched use of chargers for different battery types may cause fire hazards.
5. Dedicated Power Supply Only: Use only the supplied removable power supply model **UY600L-W546080** for charging.
6. Battery Disposal: Remove the battery and dispose of it in accordance with safety regulations before scrapping the device.

Software Management

1. Regular Software UpdatesRegularly check and upgrade the robot's operating system and control software to fix potential vulnerabilities and enhance system security.

8. After-sales Service Policy

8.1 Warranty Content

For details of the warranty content, please refer to https://www.agibot.com/filepage/292.html

