R-POWER · 多智能体机器人测评

让多机器人的可靠性，第一次可被测量、被比较、被引用。

越野场景 · 双车协同 · 故障注入 · 可复核评分

已上线	5 台	17+ 维	35 km/h
R-Eval 测评平台	R-Box 试样	统一时基采集	赛道均速

01 / 四条产品线

载体
R-ORV
可消耗越野载体，30 km/h+，单台 ≤ 3 万元

原型验证

测量
R-Box
故障注入 · 统一时基 · 防篡改

试样 5 台

评判
R-Eval
时序对齐 · 事件切片 · RRI / CRI

已上线

定义
R-SIM
实测回流仿真，收窄 sim-to-real

2027 Q4 内测

02 / 为什么需要测评

仿真跑通 99%，1% 真实故障没人采

单次沙漠实测超 45 万元，陷沙、过热、通信中断无法复现。

多机协同没有标尺

单车感知已有基准；双车接续、故障补位、通信降级仍无度量。

科研底盘接不住

≤10 km/h 、室内平地、 7.5–15 万元 / 台，是“舍不得撞”的资产。

03 / 研发闭环 · 基于 NVIDIA 机器人生态

Isaac Sim → 越野场景批量仿真

TensorRT → 模型量化与算子优化

Jetson Orin → 车载实时推理

R-Box + R-Eval 实测回流与评分

04 / 公司与联系

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香港复兴动力科技有限公司，注册号 79936367

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R-POWER · MULTI-AGENT ROBOTICS EVALUATION

Making multi-robot reliability measurable, comparable, and citable.

Off-road · multi-vehicle coordination · fault injection · auditable scoring

LIVE
R-Eval platform

5 units
R-Box prototypes

17+ dims
unified time base

35 km/h
track average

01 / FOUR PRODUCT LINES

CARRIER
R-ORV
Expendable off-road carrier, 30 km/h+, ≤¥30K/unit

Prototype validated

MEASURE
R-Box
Fault injection · unified time base · tamper-evident

5 prototypes

JUDGE
R-Eval
Temporal alignment · event slicing · RRI / CRI

Live

DEFINE
R-SIM
Field data feeds simulation, narrowing sim-to-real

Beta Q4 2027

02 / WHY EVALUATION

99% works in sim; the 1% real fault is never captured

A single desert run costs ¥450K+; sand traps, thermal shutdowns and comm drops can't be reproduced.

No yardstick for multi-agent coordination

Single-robot perception has benchmarks; hand-off, fault coverage and degraded comms do not.

Research chassis can't take the abuse

≤10 km/h, indoor floors, ¥75–150K per unit — too precious to crash.

03 / R&D LOOP · BUILT ON NVIDIA ROBOTICS

Isaac Sim → batch off-road scenarios

TensorRT → quantization & operator optimization

Jetson Orin → on-vehicle inference

R-Box + R-Eval → field data & scoring

04 / COMPANY & CONTACT

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IP
Chinese invention patent pending 202611531457.4

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