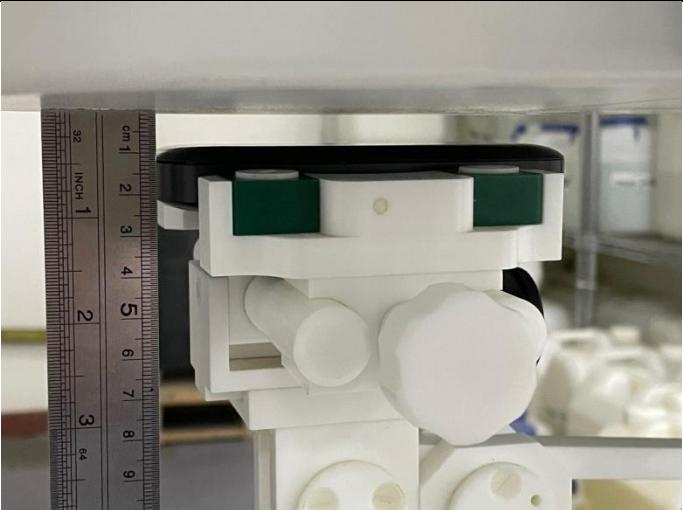
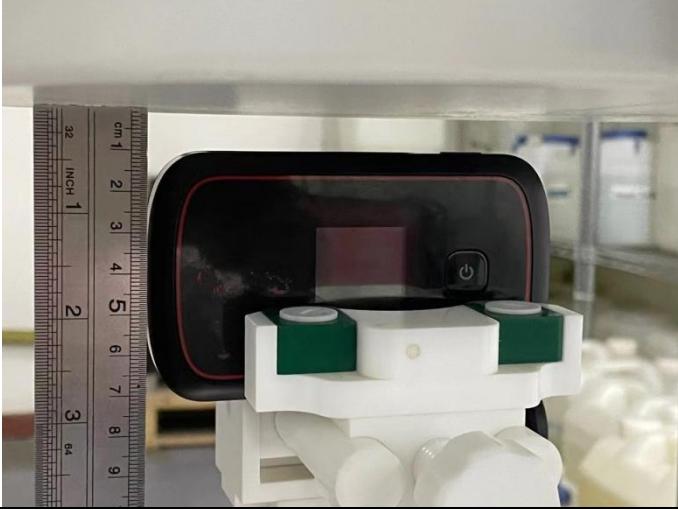
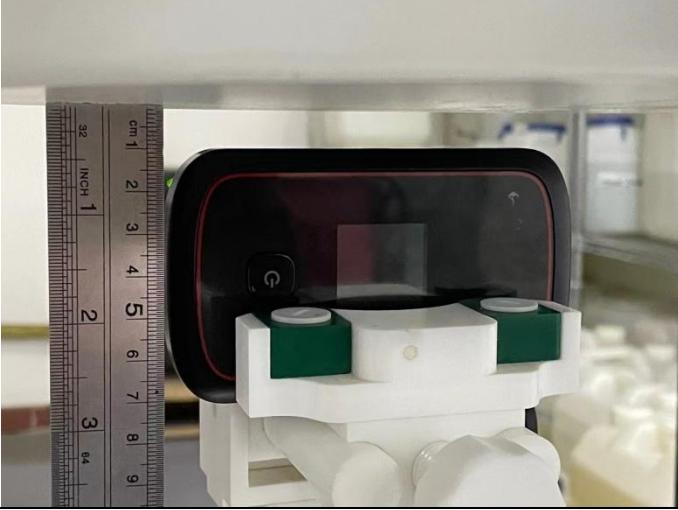
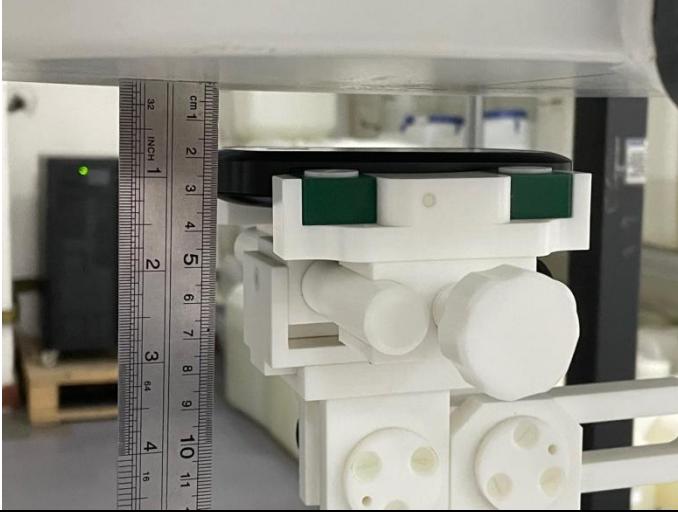
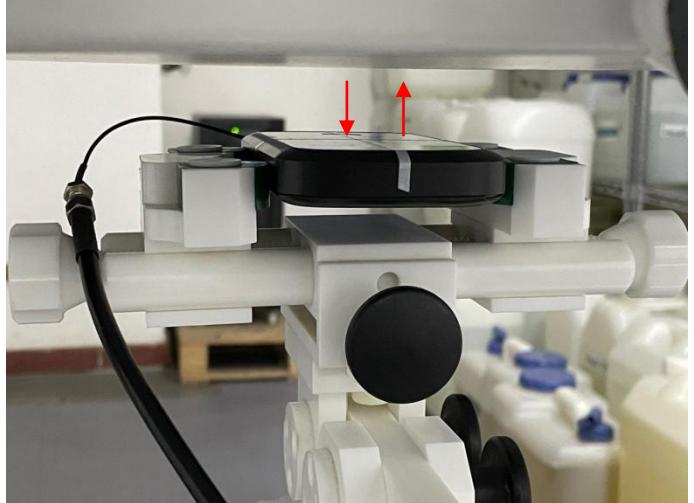
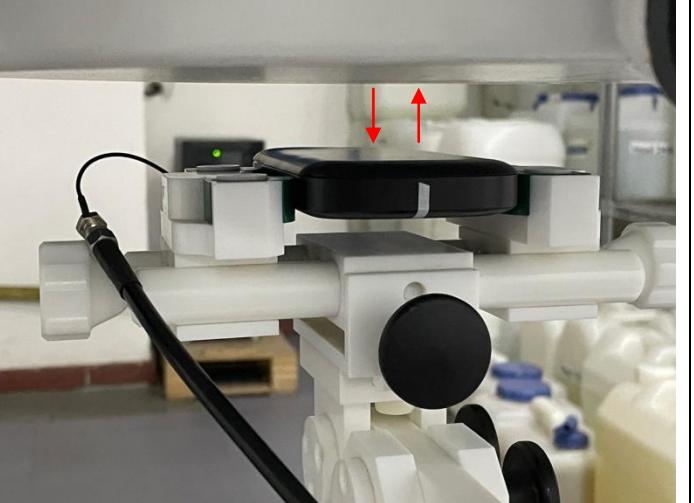
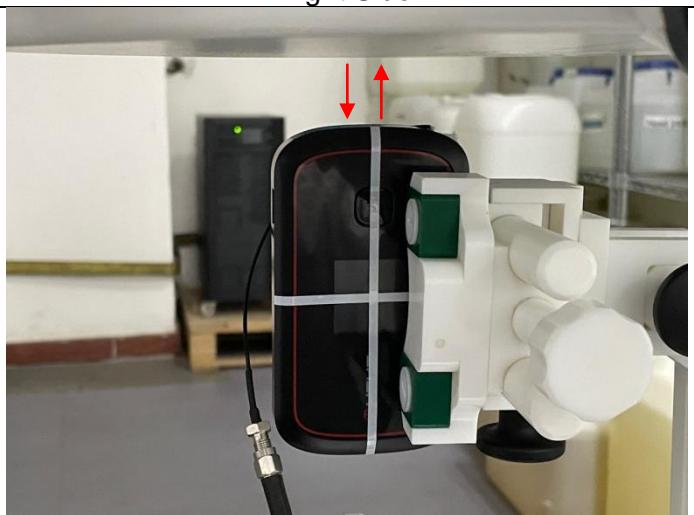


### Test Positions

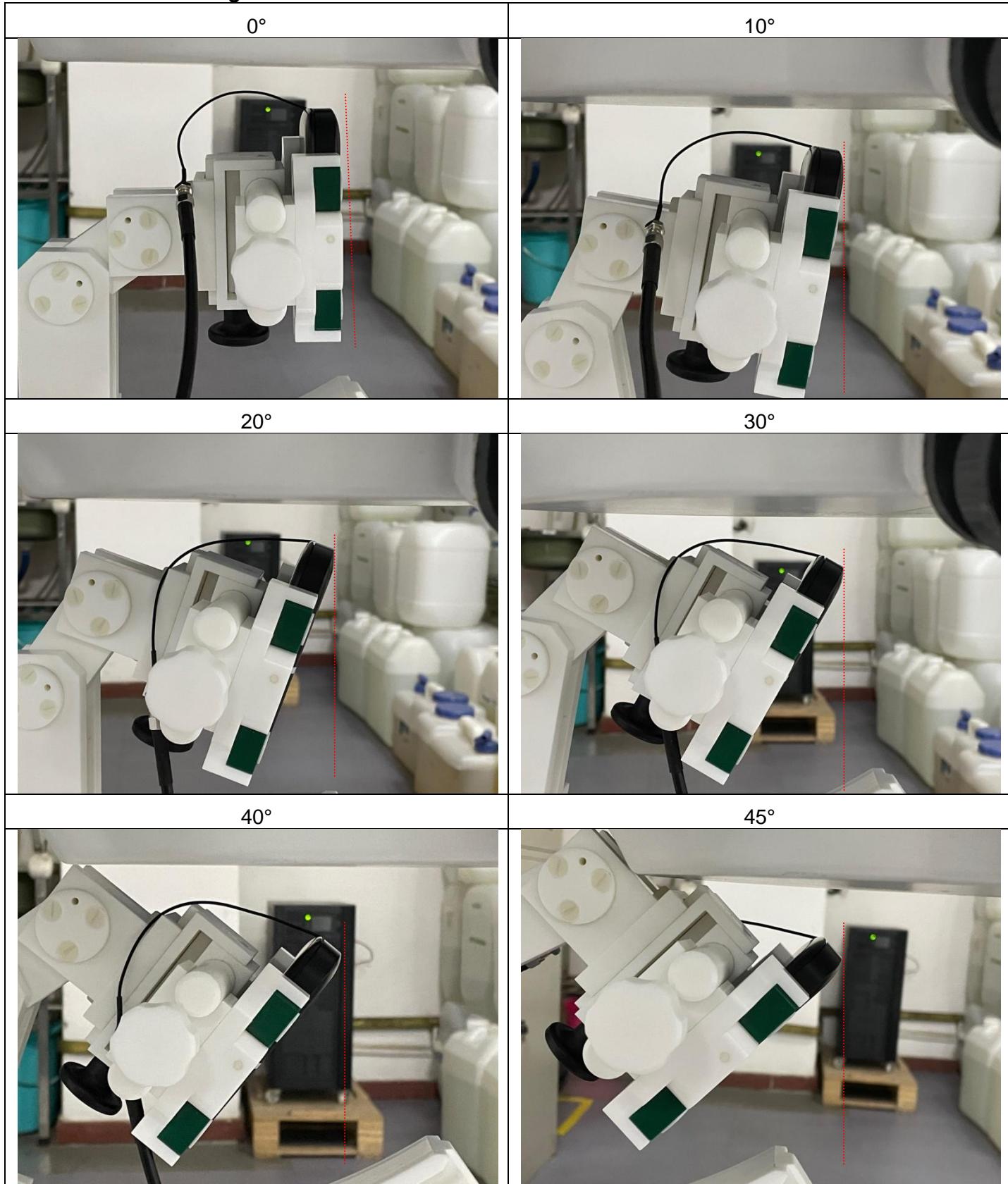
Front Side (Separation distance of 10mm)	Back Side (Separation distance of 10mm)
	
Left Side (Separation distance of 10mm)	Right Side (Separation distance of 10mm)
	

<p style="text-align: center;"><b>Top Side</b> (Separation distance of 10mm)</p> 	<p style="text-align: center;"><b>Bottom Side</b> (Separation distance of 10mm)</p> 
<p style="text-align: center;"><b>Front Side</b> (Separation distance of 18mm)</p> 	<p style="text-align: center;"><b>Back Side</b> (Separation distance of 18mm)</p> 
<p style="text-align: center;"><b>Right Side</b> (Separation distance of 18mm)</p> 	<p style="text-align: center;">N/A</p> <p style="text-align: center;">N/A</p>

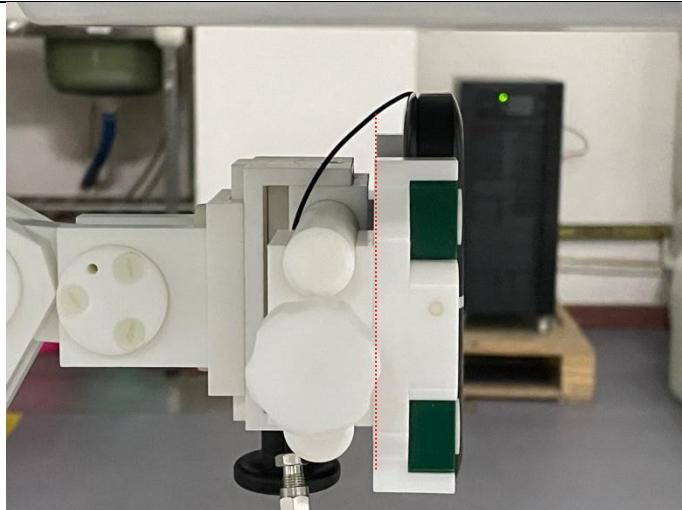
### Proximity Sensor Triggering Distances Test Positions

Front Side	Back Side
 A photograph showing a black proximity sensor mounted on a white robotic arm. Two red arrows point vertically upwards from the sensor, indicating the range of detection. The background shows a laboratory setting with various equipment and containers.	 A photograph showing a black proximity sensor mounted on a white robotic arm. Two red arrows point vertically upwards from the sensor, indicating the range of detection. The background shows a laboratory setting with various equipment and containers.
Right Side	N/A
 A photograph showing a black proximity sensor mounted on a white robotic arm. Two red arrows point vertically upwards from the sensor, indicating the range of detection. The background shows a laboratory setting with various equipment and containers.	N/A

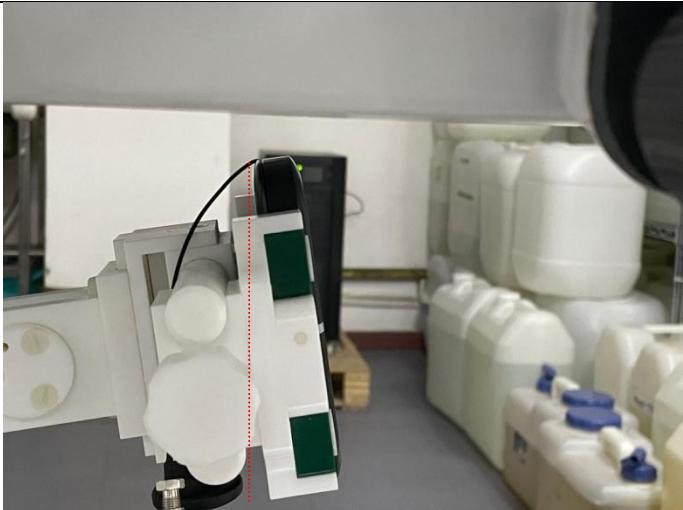
### EUT Tilt Angle Test Positions



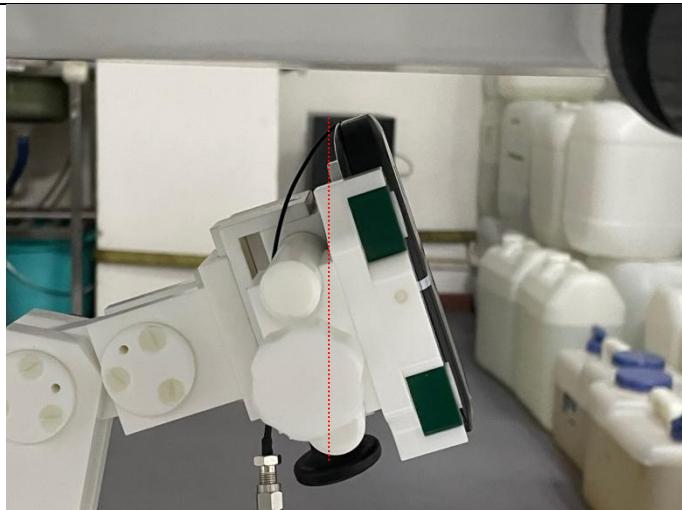
$0^\circ$



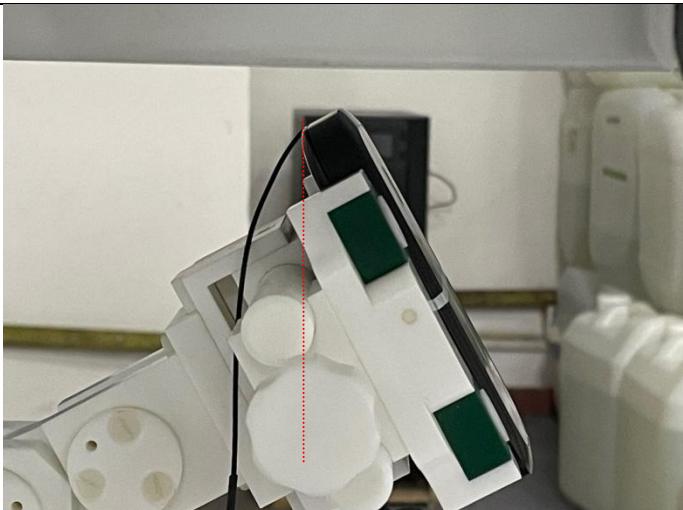
$-10^\circ$



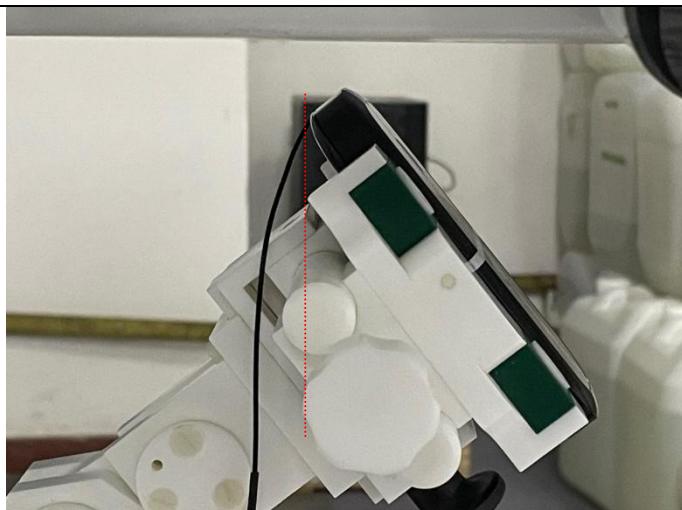
$-20^\circ$



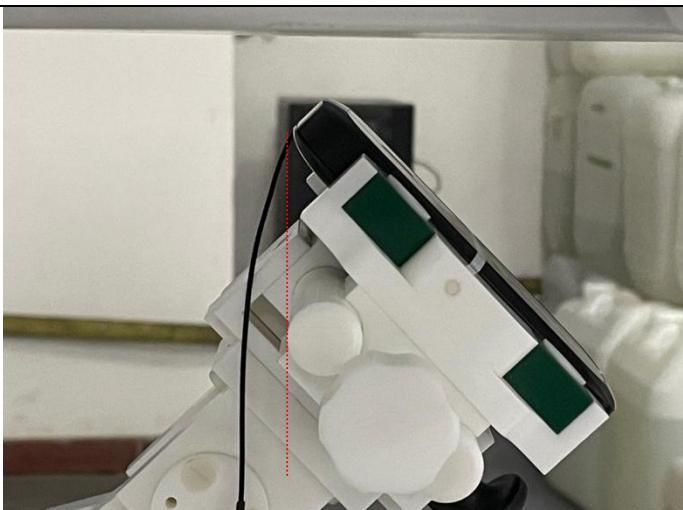
$-30^\circ$



$-40^\circ$



$-45^\circ$



END