F. No. G_C_/C.Pur/3-77/2025/0589 **Dated: 24.02.2026**

Invitation of Quotation/Rate Inquiry for Procurement of 'Robots'

National Forensic Sciences University (NFSU) intends to procure **'Robots'** from manufacturer/authorized distributors as mentioned below:

Sr. No.	Name of Item	Qty.
1.	**Robots**	As per attached Enclosure – I

The notice is hereby issued for general information of Aspirant Manufacturer/Authorized Distributors to submit their quotation, on selling of the above items.

Any query on the notice for quotation of the above items, if any, should be sent through email to **purchase_gnr@nfsu.ac.in** so as to reach on or before **27/02/2026 up to 05:00 PM**. Queries after mentioned duration will not be considered.

Last Date of submission of the Quotation/Rate is **05/03/2026 upto 05:00 PM**.

The product of all Aspirant Manufacturer/Authorized Distributor conforming to the aforesaid all/any items, may submit their Quotation/Rate inquiry for all/any items.

Vendors are permitted to participate on a **line-item basis** against the items listed in the enclosure-I. The bidder shall quote **only for those specific line items** for which they are eligible and are providing explicit confirmation of compliance. Evaluation and award shall also be carried out **item-wise** for the confirmed line items only.

The Quotation/Rate inquiry should be submitted in the prescribed format given at **Enclosure-II.**

Campus Director
NFSU, Gandhinagar

Enclosure – I

General Specification

Robots Line-Wise Items Specification

Warranty Period: Least 12 Months

Sr. No.	Product Name	Category	Parameter	Specification	Qty.
1	Mobile Robot 1	Physical Attributes	External Dimensions (L×W×H)	approximately 340 × 340 × 350 mm (13.4 × 13.3 × 13.8 in)	1.00
			Weight	approximately 3.5 – 4.0 kg (approximately 8 lbs)	
			Wheel Diameter	approximately 70 mm	
			Ground Clearance	approximately 5 mm	
			Maximum Payload	approximately 9 kg (default) / up to 15 kg (custom configuration)	
		Kinematic Performance	Maximum Linear Speed	approximately 0.3 m/s (safe mode) / approximately 0.45 m/s (unrestricted)	
			Maximum Rotational Speed	approximately 1.9 rad/s	
		Power System	Battery Type	26 Wh Li-ion (14.4 V nominal, rechargeable)	
			Charging Time	approximately 2.5 hours	
			Operating Time	approximately 2.5 – 4 hours (depending on load)	
			Power Output Interfaces	Main Battery: 14.4 V @ 1.9 A; Regulated Output 1: 12 V @ 1.3 A; Regulated Output 2: 5 V @ 0.5 A; Logic/Signal Output: 3.3 V @ 0.25 A	
		Autonomous Features	Docking System	Autonomous base-station docking for charging	
		Perception Sensors	2D LiDAR	RPLIDAR A1 – 0.15 – 12 m range, 8 kHz sampling, 360° coverage, approximately 1° resolution (or better)	
			Depth / RGB Cameras	OAK-D-PRO (4K RGB IMX378 + stereo pair OV9282 + IMU + IR projector + LED illumination) / OAK-D-LITE (4K RGB IMX214 + stereo OV2511) (or better)	

	Other Sensors	2× front bumpers, 2× wheel encoders, 4× cliff IR sensors, 6× IR obstacle sensors, 1× optical flow sensor
Inertial & Feedback Sensors	IMU / Gyro / Accel	3D gyroscope + 3D accelerometer + battery monitor + odometry sensors
Actuation & Indicators	Drive Motors	2× DC drive motors (wheel encoders integrated)
	Visual / Audio Indicators	6× RGB LED rings, 5× status LEDs, 1× speaker
On-board Computing	Main Computer	Raspberry Pi 4 B (4 GB RAM) or better
	Operating System	Ubuntu 20.04 LTS or later
	Middleware Stack	ROS 2 (latest distribution)
	Weight (with SBC, battery, sensors)	approximately 1.5 – 2.0 kg
	Maximum Payload	approximately 30 kg
	Climbing Threshold	less than or equal to 10 mm
Kinematic Performance	Maximum Linear Speed	approximately 0.25 m/s
	Maximum Rotational Speed	approximately 1.8 rad/s (approximately 104°/s)
Power System	Battery	11.1 V, 1800 mAh (approximately 20 Wh) Li-Po, 5C discharge rate
	Charging Time	approximately 2.5 hours
	Operating Time	approximately 2 hours (typical load)
	Power Outputs	Regulated Output 1: 12 V @ 1 A; Regulated Output 2: 5 V @ 4 A; Logic/Signal Output: 3.3 V @ 0.8 A
	Power Adapter	12 V DC, 5 A (100–240 V AC input)
Control & Computing	Single Board Computer (SBC)	Raspberry Pi 4 or better
	Microcontroller (MCU)	32-bit ARM Cortex-M7, 216 MHz (approximately 462 DMIPS)
	Remote Controller	RC-100B + BT-410 (Bluetooth 4.0 / BLE)

		Sensing & Perception	Laser Distance Sensor (LDS)	360° LiDAR (LDS-02 class or better)
			Camera	Raspberry Pi Camera Module v2.1 or better
			IMU	3-axis gyroscope + 3-axis accelerometer
		Communication & Interfaces	Peripheral Interfaces	UART ×3, CAN ×1, SPI ×1, I²C ×1, ADC ×5, 5-pin OLLO ×4
			Expansion Ports	GPIO (18 pins), Arduino-compatible (32 pins)
			DYNAMIXEL Ports	RS-485 ×3, TTL ×3
		Actuation	Motors / Actuators	DYNAMIXEL XL430-W250 and XM430-W210 servos
		Indicators & Controls	LEDs	4× user LEDs, 3× status LEDs (board, power, Arduino)
			Buttons / Switches	2× push buttons, 1× reset, 2× DIP switches
			Audio	Programmable beep sequences
		Connectivity & Firmware	PC Interface	USB (data and firmware)
			Firmware Upgrade	via USB or JTAG
		Operating Environment	Nominal Voltage	11.1 V
			Typical Operating Duration	approximately 2 hours (typical load)
			Weight (with SBC, battery, sensors)	approximately 1 – 1.2 kg
			Maximum Payload	approximately 15 kg
			Climbing Threshold	less than or equal to 10 mm
		Kinematic Performance	Maximum Linear Speed	approximately 0.22 m/s
			Maximum Rotational Speed	approximately 2.8 rad/s (approximately 163°/s)
		Power System	Battery	11.1 V Li-Po (approximately 1800 mAh / 20 Wh, 5C discharge rate)

			Charging Time	approximately 2.5 hours
			Operating Time	approximately 2.5 hours (load-dependent)
			Power Outputs	Regulated Output 1: 3.3 V @ 0.8 A; Regulated Output 2: 5 V @ 4 A; Regulated Output 3: 12 V @ 1 A
			Power Adapter (SMPS)	Input: 100–240 V AC (50/60 Hz, 1.5 A max); Output: 12 V DC @ 5 A
		Control & Computing	Single Board Computer (SBC)	Raspberry Pi 4 or better
			Microcontroller (MCU)	32-bit ARM Cortex-M7, 216 MHz (approximately 462 DMIPS)
			Remote Controller	RC-100B + BT-410 (Bluetooth 4.0 / BLE)
		Sensing & Perception	Laser Distance Sensor (LDS)	360° LiDAR (LDS-02 class or better)
			IMU	3-axis gyroscope + 3-axis accelerometer
		Communication & Interfaces	Peripheral Connections	UART × 3; CAN × 1; SPI × 1; I²C × 1; ADC × 5; OLLO × 4
			Expansion Pins	GPIO (18 pins); Arduino-compatible (32 pins)
			DYNAMIXEL Ports	RS-485 × 3; TTL × 3
		Actuation	Motors / Actuators	DYNAMIXEL XL430-W250 and XM430-W210
		Indicators & Controls	LEDs	4× user LEDs; 3× status LEDs (board, Arduino, power)
			Buttons / Switches	2× push buttons; 1× reset; 2× DIP switches
			Audio	Programmable beep sequences
		Connectivity & Firmware	PC Interface	USB (data and firmware)
			Firmware Upgrade	via USB or JTAG
		Operating Environment	Nominal Voltage	11.1 V
			Typical Operating Duration	approximately 2.5 hours (load-dependent)

				Tire Diameter	approximately 65 mm
				Weight	approximately 2.0 – 2.5 kg (assembled)
			Drive & Actuation	Motors	Dual 37-520 metal encoder motors (1:30 reduction ratio, approximately 333 RPM idle speed)
				Encoders	11-wire AB-phase Hall sensors (wheel odometry supported)
			Control & Computing	Main Controller (SBC)	NVIDIA Jetson Nano 4 GB B01 Dev Kit or better
				Microcontroller	Raspberry Pi RP2040 chip
				Operating Environment	ROS-based system (Ubuntu / JetPack SDK)
			Sensing & Perception	IMU Sensor	MPU-9250 or better (3-axis gyroscope + 3-axis accelerometer + magnetometer)
				LiDAR	RPLIDAR A1 or better (360° scanning, 60° effective ranging sector for mapping)
				Camera	IMX219-160 or better (160° FOV RGB camera, with acrylic mount)
				Audio System	Dual microphones and dual speakers (intelligent speech interface)
			Communication & Connectivity	Wireless	Intel AC8265 Wi-Fi module with dual antennas
				External Interfaces	USB adapter, GPIO ports, and serial expansion interfaces
			Additional Components	Accessories	Cooling fan, camera holder, screw pack, wireless gamepad
				Navigation / Mapping	Full SLAM and autonomous navigation support under ROS
			Software Stack	Development Framework	ROS / ROS JetPack SDK environment
				Control Modes	Remote control via wireless gamepad or ROS teleoperation
				Movable Parts	Head, Neck, Mouth, Ears, Tail, 4 Limbs (front & rear)
			Dimensions & Weight	Size (W × H × D)	approximately 180 × 290 × 305 mm (standing posture)
				Weight	approximately 2.2 kg

		Power System	Power Consumption	approximately 14 W	
			Battery Duration	approximately 2 hours of continuous operation	
			Charging Time	approximately 3 hours	
			Power Supply	Rechargeable internal Li-ion battery	
		Computing & Sensing	Processor	64-bit quad-core CPU or better	
			Cameras	2× cameras — front RGB camera & SLAM (mapping) camera	
			Microphones	4× omnidirectional microphones	
			Speakers	1× integrated speaker	
			Display	2× OLED panels (eyes)	
			Sensors	Time-of-Flight (depth), distance sensors, tactile sensors (back, head, jaw), pressure and capacitive pads (paws), dual IMU (3-axis gyroscope + 3-axis accelerometer for head and torso), light sensor, and motion sensor	
		Connectivity & Interfaces	Wireless Communication	LTE mobile data and Wi-Fi (IEEE 802.11 b/g/n @ 2.4 GHz)	
			Terminals	Charging pins and SIM card slot	
			Buttons & Switches	Power, volume, and network mode switches	
			Indicators	Status LED and network LED	
		Accessories & Docking	Included Components	Charging station (stand and mat), AC adapter, power cord, pink ball, SIM card, and documentation	
2	Biomimetic Robot 2	Physical Attributes	Dimensions (L × W × H)	approximately 390 × 360 × 210 mm	1.00
			Weight	approximately 2.5 – 3.5 kg	
			Material / Frame	Full-metal aluminum alloy (anodized)	
			Number of Legs	approximately 6	

			Power System	Battery	11.1 V Li-Po 3500 mAh (5C discharge rate)
				Continuous Operation	approximately 60 minutes of continuous use
			Computing & Control	Main Controller	ROS controller with ROS expansion board
				Operating System	Ubuntu 18.04 LTS with ROS Melodic or later
				Programming Languages	Python, C, C++, and JavaScript
				Storage	32 GB TF card
				Control Interfaces	Computer, smartphone, and handheld controller
			Sensors & Perception	LiDAR Modules	EAI G4 LiDAR or better (4–9 kHz scan rate, 16 m range) and SLAMTEC C1 Time-of-Flight (ToF) or better LiDAR
				Depth Camera	DaBai 3D structured-light depth camera or better (approximately 0.2–0.5 m range; multi-platform support)
				Camera	HD wide-angle camera or better (approximately 180° horizontal and vertical field of view)
				Microphone Array	iFLYTEK 6-channel microphone array or better (voice command and noise reduction supported)
				Display	OLED status display
			Actuation System	Servos	HX-35H intelligent serial bus servo motors
			Communication & Connectivity	Interfaces	USB, Wi-Fi, and Ethernet
				Software Support	ROS-based PC software and Android / iOS mobile applications
			Development Framework	Platform	ROS-based multi-sensor robotic system
				Weight	approximately 2.3 – 2.5 kg
				Degrees of Freedom (DOF)	approximately 24 DOF
				Locomotion Speed	approximately 0.20 m/s (20 cm/s)
			Computation & Control	Main Controller (SBC)	Raspberry Pi 5 (8 GB RAM) or better

				CPU Architecture	Broadcom BCM2711 quad-core Cortex-A72
				Storage Media	32 GB microSD card
				Operating System	Ubuntu or ROS-based environment
				PC Software Interface	AiNex Visual Action Editor
				Mobile App Support	WonderROS (Android and iOS)
			Sensing & Perception	Camera	1 MP manual-focus camera with 120° wide-angle field of view or better
				IMU Module	3-axis gyroscope, 3-axis accelerometer, and 3-axis compass
				Joint Feedback Parameters	Voltage, Position, and Temperature
			Actuation System	Servos	HX-35H serial bus servo, HX-35HM magnetic encoder servo, and HX-12H serial bus servo or better
			Power System	Battery	11.1 V Li-Po, 3500 mAh (5C discharge rate)
				Power Mode	Rechargeable battery or optional external DC power supply
			Connectivity & Interfaces	Communication & Connectivity	Bluetooth and Wi-Fi via Raspberry Pi 5
				Weight	approximately 1.8 kg
				Frame Material	Hard aluminum alloy
				Degrees of Freedom (DOF)	approximately 17 DOF
			Perception & Sensing	Detection Range	approximately 2 – 400 cm
				Voice Recognition Module	WonderEcho (48 × 24 × 10.5 mm; 2 MB flash, 60 KB RAM, 5 V DC; I²C interface; LEGO-compatible mount)
			Control & Computing	Main Controller	Humanoid robot servo controller with Arduino Nano or better
				Expansion Board	ESP32 wireless expansion or better
				Operating Environment	Embedded ROS-compatible control firmware (latest version)

			Control Modes	Computer control or infrared remote control
		Programming & Software	Supported Languages	Arduino IDE, Scratch (block-based), and Python
			Software Platform	Cross-platform PC and embedded systems
		Actuation System	Servos	LX-824HV high-voltage bus servo and LFD-01M anti-blocking servo or better
		Power System	Battery	11.1 V Li-ion, 2000 mAh (10C discharge rate)
			Power Supply	Rechargeable DC battery module
		Communication & Interfaces	Connectivity	USB, I²C, and wireless (via ESP32)
			Voice Control	Wake-word and command recognition via WonderEcho module
		Development Framework	Supported Platforms	Arduino, Python, and Scratch (for educational and research applications)
			Weight	approximately 3.5 kg
			Material / Chassis	Full-metal aluminum alloy (anodized finish)
			Degrees of Freedom (DOF)	approximately 6 DOF
			Number of Arms	approximately 1
		Power System	Battery	11.1 V Li-Po, 6000 mAh
			Continuous Operation Time	approximately 60 minutes of continuous use
			Charging / Power Input	12 V DC SMPS-compatible
		Computing & Control	Main Controller (SBC)	NVIDIA Jetson Orin Nano (8 GB) or better
			Secondary Controller	ROS controller with ROS expansion board (latest version)
			Operating System	Ubuntu 18.04 LTS with ROS Melodic or later
			Storage	32 GB TF card

			Programming Languages	Python, C, C++, and JavaScript	
		Sensors & Perception	LiDAR Modules	SLAMTEC A1 and EAI G4 LiDAR units or better	
			Depth Camera	ORBBEC structured-light depth camera (1280 × 1024 @ 7 fps, USB 2.0) or better	
			Microphone Array	6-microphone array with 360° pickup range, approximately 10 m detection distance, echo cancellation, and offline voice command capability	
		Actuation System	Servo Motors	HTS-20H serial bus servos or better	
		Display & Interfaces	LCD Screen	7-inch touch display (1024 × 600 px, USB / HDMI / power ports)	
			Communication Interfaces	USB, Wi-Fi, and Ethernet	
			Control Modes	Mobile application, gamepad remote, or PC control.	
		Software & Integration	PC / Mobile Applications	Remote control software (Windows, iOS, and Android)	
			Voice Interaction	Wake-word and custom offline voice commands (up to 10 words each)	
3	Defence Robot 2	Physical Attributes	Chassis Type	Tank-type tracked chassis	1.00
			Dimensions (L × W × H)	approximately 345 × 245 × 660 mm	
			Weight	approximately 4.5 kg	
		Power & Drive System	Motors	Integrated voltage, position, and temperature feedback	
			Encoders	1024-line AB-phase quadrature encoders (high precision) or better	
			Servo Types	HTS-20H, HTS-21H, HTD-35H, and HX-12H serial-bus intelligent servos or better	
		Computing & Control	Main Controller	NVIDIA Jetson Orin Nano (8 GB) or better	
			ROS Controller	NVIDIA Jetson Nano B01 or equivalent	
			Operating System	Ubuntu 18.04 LTS with ROS Melodic or later	
			Software / Applications	PC control software and Android / iOS mobile applications	

			Programming Languages	Python, C, C++, and JavaScript
		Sensors & Perception	LiDAR Modules	SLAMTEC A1 and EAI G4 LiDAR units or better
			Depth Camera	ORBBEC active binocular structured-light depth camera (640 × 480 @ 30 fps, 0.3–3 m range, less than 2 W power consumption) or better
			Encoder Feedback	Integrated wheel encoders for odometry
		Interfaces & Communication	Control Interfaces	USB serial, CAN bus, Bluetooth application, and remote controller
			Connectivity	USB, Wi-Fi, and Ethernet
			USB Expansion	5 A high-current USB HUB board
		Display & Interaction	LCD Screen	7-inch touch display (1024 × 600 px, USB / HDMI / power ports; Ubuntu and Raspberry Pi compatible)
		Software Environment	Supported Platforms	Android, Linux, and Windows
		Build & Integration	Material	Reinforced alloy chassis (anodized finish)
		Operational Overview	Control Modes	Mobile application, remote handle, or PC via USB / Wi-Fi
			Typical Use Case	Mobile defense and autonomous surveillance robot
			Weight	approximately 1.5 kg
			Structure Type	Sliding-rail robotic arm structure
			Material	Metal and carbon-fiber composite
		Kinematics & Payload	Degrees of Freedom (DOF)	4 + 1 (gripper / tool axis)
			Maximum Payload	approximately 0.45 kg
		End Effectors	Tools Supported	Electric suction nozzle, electromagnet suction cup, precision gripper, and pen attachment
		Control & Computation	Main Controller	ROS-based embedded controller or better
			Operating System	Ubuntu with ROS framework or later versions

			Programming Languages	Python, C, C++, and JavaScript	
			Control Interfaces	PC, smartphone, wireless gamepad, or mouse	
			Storage	32 GB TF card	
		Power & Connectivity	Power Supply	12 V @ 5 A DC (external adapter)	
			Communication Interfaces	USB, Wi-Fi, and Ethernet	
		Servo & Actuation	Servo Types	HTS-35H and LFD-01M intelligent serial servos or better	
		Software & Development	Development Platform	ROS (Robot Operating System)	
			Application Software	PC control software and Android / iOS mobile applications	
4	Industrial Robot 2	Physical Attributes	Dimensions (L × W × H)	approximately 340 × 165 × 530 mm	1.00
			Weight	approximately 2.5 kg	
			Frame Material	Full-metal aluminum alloy with anodized surface finish	
		Control & Computation	Primary Controller	NVIDIA Jetson Orin NX (8 GB) or better	
			Secondary Controller	STM32F407VE16 embedded controller with FreeRTOS (or better)	
			Operating System	Ubuntu 20.04 with ROS Noetic, Ubuntu 18.04 with ROS Melodic, or ROS 2 on Ubuntu 22.04 (latest supported versions)	
			Storage	128 GB SSD	
			USB Expansion	5 A high-current USB HUB board	
		Power System	Power Supply	12 V @ 5 A DC or 19 V @ 2.37 A external adapter	
		Perception & Sensors	Depth Camera	Orbbec Gemini Plus 3D depth camera (active binocular structured-light) or better	
			Audio System	Integrated 6-microphone array	
			Display	7-inch HD touchscreen (USB / HDMI)	

		Communication & Interfaces	Connectivity	USB, Wi-Fi, and Ethernet
			Control Interfaces	USB serial, CAN bus, Bluetooth app, RC transmitter, and PC
			Programming Languages	Python, C, C++, and JavaScript
		Actuation System	Servo Models	HTS-21H, HTD-35H, HX-12H smart bus servos or better
		Software & Development	Development Platform	ROS and ROS 2 frameworks
			Application Software	iOS and Android applications for remote control
			Supporting Resources	Comprehensive documentation, source code repositories, system images, and user tutorials.

Enclosure - II

Invitation of Quotation/Rate Inquiry
Procurement of *Robot(s)*

(PRODUCE ON THE LETTER HEAD OF THE FIRM)

No_____ Date_____

To,
The Campus Director
National Forensic Sciences University (NFSU)
Police Bhavan Road, Sector 9,
Gandhinagar, Gujarat 382007

Sub: Invitation of Quotation/Rate Inquiry for Procurement of Robots mentioned in enclosure - I

Sir,

With reference to your Quotation/Rate Inquiry, vide no.....dated.....

Please find the quoted rates by us: -

SI. NO.	Name of the Item	Unit Price	Qty.	Total Price	Discount	Net Price	GST	Any Other Charge	Total Cost

Further, I also abide by the terms and conditions of the Quotation/Rate Inquiry as given in **Annexure - A.** The other details and documents as desired by the procuring Authority are enclosed at **Annexure – B & C.**

Yours faithfully,

Signature_____
Full Name_____
Designation_____
MOBILE_____
Email Id_____
Stamp_____

Annexure - A

Invitation of Quotation/Rate Inquiry/Objections for Procurement of Robot(s)

(PRODUCE ON THE LETTER HEAD OF THE FIRM)

Terms & conditions

1. Quotation sent by **Registered post/ Speed post** in sealed cover will only be accepted.
2. The bidder should clearly mention whether they are manufacturer or Authorized Dealer/ Distributor/Supplier of the manufacturer. In the case of authorized Distributor /Dealer /Supplier, valid **Authorization letter issued by the manufacturer** in favour of the Distributor should be submitted along with the quotation.
3. Authorized Dealer/ Distributor/Supplier must agree to provide product/tool as mentioned in **enclosure-I (General Specification).**
3. Quotation received after the last date & time is liable to be rejected.
4. GST will be applicable as per GoI norms.
5. The price quoted by the bidder should not be more than the price prevailing in market. The bidder must enclose a Price Reasonability Certificate in the prescribed format and/or past PO to government organization/PSUs/Education Institutions.
6. The bidder conditions mentioned in the quotation, if any, shall not be binding on NFSU, Gandhinagar Campus.
7. Quotation should be preferably, typewritten and every correction in the quotation should invariably be signed be the bidder, failing which, the quotation is liable to be rejected.
8. In the quotation, Name of the item & Catalogue number should be the same as mentioned on page 1.
9. Any dispute concerning any Terms and Conditions of the Quotation and/or the supply of items, will be subject to Gujarat jurisdiction only.
10. Price should be quoted on the vendor's Letter head, duly stamped and signed.
11. Items should be delivered within 10 days at NFSU, Gandhinagar Campus, from the date of issue of purchase order. The liquidated charges @ ½ % per week or part thereof shall be imposed if supply made after expire of delivery period subject to maximum 10% of the total value of goods/contract value.
12. Validity of quotation should be for a minimum period of 03 months (90 days).
13. The vendor shall be required to deposit PGB @ 5 % of the total PO value with Validity of 14 Months.
14. The payment shall be released to the firm within a period of 30 days of receipt and successful installation of the ordered items. No advance Payment to the firm shall be considered except in case of unavoidable circumstances.
15. If, in the price structure quoted by a bidder, there is discrepancy between the unit price and the total price (which is obtained by multiplying the unit price by the quantity), the unit price shall prevail and the total price will be corrected accordingly. If there is a discrepancy between the amount expressed in words and figures, the amount expressed in words shall prevail
16. The Director, NFSU, Gandhinagar, Campus reserves the right to reject any or all quotations without assigning any reason.

Annexure - B

Invitation of Quotation/Rate Inquiry/Objections for Procurement of Robot(s)

(PRODUCE ON THE LETTER HEAD OF THE FIRM)

BIDDER'S INFORMATION

S.No	Particulars	Remarks
1	Name of the firm	
2	State whether, you are a manufacturer or Authorized Distributor.	
3	Name of Authorized person/Representative of the firm with contact details.	
4	Name of Authorized person/Representative of the firm with whom, the negotiations may be done, if required (The person must be empowered of taking decisions during the negotiation)	
5	Complete Address of the firm with Telephone No., Fax No., Email etc.	
6	Company Registration Number (Attach copy of Registration Certificate)	
7	GST Registration Number (Attach copy of GST Certificate)	
8	Whether you have supplied the 'Robot(s)" to any other Govt. Organization within last one year from 01.12.2024 to 31.12.2025. (YES/NO)	
8 (a)	If yes, attach copy of the Purchase order Clearly indicating the price of the item	
8 (b)	If no, attach Price Reasonability Certificate in the prescribed format (Annexure-C)	
9	Attach a copy of the turnover Certificate for last 03 financial years issued by a CA with UDIN Number	
10	Attach a Non-Black Listing Certificate on the letter head of the firm	

11	In case of Authorized Distributor, enclose a copy of the valid authorization certificate issued by the manufacturer	

Declaration: - I shall abide by all the terms and conditions as given above.

Signature_____
Full Name_____
Designation_____
MOBILE_____
Email Id_____
Stamp_____

Annexure- C

PRICE REASONABILITY CERTIFICATE

(To be given by the vendor on the Letter Head of the company/Firm)

It is Certified that the RATES quoted by us vide tender/quotation no_____ dated_____ for supply of goods/services etc. is not more than the rates charged to other Government Organization/Research Laboratories etc., for same supplies made by our firm, in the recent past, preferably within two years. If at any stage, it has been found that the quoted rate to the NFSU, Gandhinagar, Campus, is higher than the rates charged to above mentioned institutions, then in such a situation/condition, NFSU, Gandhinagar, Campus, shall have the right to take legal action against us, for recovery of excess rates.

Yours faithfully,

Authorized signatory of Bidder with Seal

Name_____

Designation_____