

ALLNAMES:(Agile Robots AG)

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Machine translation

1. [WO/2021/204393](#) ROBOT ARM HAVING AN ARTICULATED JOINT

WO - 14.10.2021

Int.Class [B25J 9/10](#) Appl.No PCT/EP2020/060200 Applicant AGILE ROBOTS AG Inventor DÜRR, Daniel Mark

The invention relates to a robot arm having at least two limbs [2], which are connected to one another at their ends via an articulated joint [10] so that they can be pivoted relative to one another about a rotation axis [A], the two limbs [2] each comprising at least one joint portion [3] and a transition region [4] adjoined thereto and each extending in a longitudinal direction [L]. According to the invention, the transition region [4] of at least one of the limbs [2, 2a] has a circumferential edge [6] which, when considered from a direction running transverse to the rotation axis [A] and transverse to the longitudinal direction [L], crosses a parting line [9] between the two joint portions [3] and runs at a predefined distance radially outside the joint portion [3] of the other limb [2], the circumferential edge [6] running at a distance, in relation to the rotation axis [A], of less than 25 mm outside the surface of the joint portion [3] of the other limb [2] arranged beneath. In addition, a portion of the circumferential edge [6] extends obliquely to the rotation axis [A] when considered from a direction running transverse to the rotation axis [A] and transverse to the longitudinal direction [L].

2. [202247030724](#) ROBOT ARM HAVING AN ARTICULATED JOINT

IN - 03.06.2022

Int.Class [B60C /](#) Appl.No 202247030724 Applicant AGILE ROBOTS AG Inventor DÜRR, Daniel Mark

The invention relates to a robot arm having at least two limbs [2], which are connected to one another at their ends via an articulated joint [10] so that they can be pivoted relative to one another about a rotation axis [A], the two limbs [2] each comprising at least one joint portion [3] and a transition region [4] adjoined thereto and each extending in a longitudinal direction [L]. According to the invention, the transition region [4] of at least one of the limbs [2, 2a] has a circumferential edge [6] which, when considered from a direction running transverse to the rotation axis [A] and transverse to the longitudinal direction [L], crosses a parting line [9] between the two joint portions [3] and runs at a predefined distance radially outside the joint portion [3] of the other limb [2], the circumferential edge [6] running at a distance, in relation to the rotation axis [A], of less than 25 mm outside the surface of the joint portion [3] of the other limb [2] arranged beneath. In addition, a portion of the circumferential edge [6] extends obliquely to the rotation axis [A] when considered from a direction running transverse to the rotation axis [A] and transverse to the longitudinal direction [L].

3. [3866113](#) IMAGE SEGMENTATION METHODS AND APPARATUS

EP - 18.08.2021


Int.Class [G06T 7/70](#) Appl.No 20157756 Applicant AGILE ROBOTS AG Inventor SCHULTE PATRICK

An image processing method and apparatus for segmenting an image to find objects of interest in a scene. An image is subdivided into a mesh of finite elements. A vector is assigned to each finite element. Each vector is anchored in its finite element and has a direction that is initially set to an arbitrary value. A pre-trained neural network is applied to determine directions for the vectors, wherein the neural network has been previously trained to minimise cost in a loss function where cost is minimised when all vectors associated with an object of interest are pointing to a common point lying within a boundary associated with that object. Objects of interest in the image are identified through analysis of the vector directions, since all vectors associated with a particular object will point towards a common centre point, thus also automatically defining the object boundary also.

4. [202020106710](#) MODULARER ROBOTER UND VERBINDUNGSSTANGE ZUM VERTIKALEN ANORDNEN VON DOPPELGELENKEN

DE - 14.01.2021

Int.Class [B25J 17/00](#) Appl.No 202020106710 Applicant Agile Robots AG Inventor

Modularer Roboter, der eine Verbindungsstange [1] und ein Gelenk umfasst, wobei die Verbindungsstange [1] dazu dient, Doppelgelenke vertikal anzuordnen, dadurch gekennzeichnet, dass es sich bei der Verbindungsstange [1] um eine gesonderte Struktur handelt, die einen Hauptkörper, der im wesentlichen L-förmig ist, und einen Flansch [3] zum Verbinden mit dem Gelenk umfasst, wobei der Flansch [3] eine gesondert bearbeitete Komponente ist und der Flansch [3] durch ein Verbindungselement an der Verbindungsstange [1] befestigt ist. 

5. [WO/2021/104950](#) MODULAR ROBOT JOINT, ENCODER READING HEAD POSITION ADJUSTMENT MECHANISM AND METHOD FOR ADJUSTING THE POSITION OF AN ENCODER READING HEAD

WO - 03.06.2021

Int.Class [B25J 9/10](#) Appl.No PCT/EP2020/082435 Applicant BEIJING SILING ROBOT TECHNOLOGY CO., LTD. Inventor CHEN, Zhaopeng

The invention discloses a modular robot joint, encoder reading head position adjustment mechanism and method for adjusting the position of an encoder reading head, the encoder reading head position adjustment mechanism is disposed on one side of the encoder reading head bracket, and includes a lower support and an upper support, the lower support and the upper support are connected to each other and positioned by a positioning connecting member, the upper support is pressed tightly against the lower support by a pressing connecting member, the encoder reading head is fixed to the upper surface of the upper support and is opposite to the encoder magnetic ring, the encoder magnetic ring is fixed to the motor shaft or the hollow shaft, the distance between the lower support and the upper support can be adjusted by adjusting the pressing connecting member and positioning connecting member, so that the axial distance between the reading head and the magnetic ring can be adjusted to a predetermined value, the processing accuracy of related parts on the dimensional chain is reasonably reduced, and the processing cost is reduced too, and the relative distance between the reading head and the magnetic ring is easy to adjust when the robot joint is assembled and debugged, thus achieving good technical results.

6. [202247030722](#) MODULAR ROBOT JOINT, ENCODER READING HEAD POSITION ADJUSTMENT MECHANISM AND METHOD FOR ADJUSTING THE POSITION OF AN ENCODER READING HEAD


IN - 03.06.2022

Int.Class [B25J/](#) Appl.No 202247030722 Applicant BEIJING SILING ROBOT TECHNOLOGY CO., LTD. Inventor CHEN, Zhaopeng

The invention discloses a modular robot joint, encoder reading head position adjustment mechanism and method for adjusting the position of an encoder reading head, the encoder reading head position adjustment mechanism is disposed on one side of the encoder reading head bracket, and includes a lower support and an upper support, the lower support and the upper support are connected to each other and positioned by a positioning connecting member, the upper support is pressed tightly against the lower support by a pressing connecting member, the encoder reading head is fixed to the upper surface of the upper support and is opposite to the encoder magnetic ring, the encoder magnetic ring is fixed to the motor shaft or the hollow shaft, the distance between the lower support and the upper support can be adjusted by adjusting the pressing connecting member and positioning connecting member, so that the axial distance between the reading head and the magnetic ring can be adjusted to a predetermined value, the processing accuracy of related parts on the dimensional chain is reasonably reduced, and the processing cost is reduced too, and the relative distance between the reading head and the magnetic ring is easy to adjust when the robot joint is assembled and debugged, thus achieving good technical results.


7. [202020106711](#) KABEL-TRAGSTRUKTUR UND MIT EINER SOLCHEN VERSEHENER MODULARER ROBOTER DE - 04.03.2021

Int.Class [H02G 11/00](#) Appl.No 202020106711 Applicant Agile Robots AG Inventor

Kabel-Tragstruktur dadurch gekennzeichnet, dass sie einen Einfädellring [81, 81'], einen Tragarm [82, 82'] und einen Befestigungsteil [83, 83'] aufweist, wobei ein durchgehendes Loch in einem vom Einfädellring [81, 81'] umgebenen Teil ausgebildet ist und das zu tragende Kabel durch das durchgehende Loch hindurch treten kann, der Befestigungsteil [83, 83'] verwendet wird, um die Kabel-Tragstruktur an anderen Komponenten zu befestigen, und der Tragarm [82, 82'] mit dem Einfädellring [81, 81'] und dem Befestigungsteil [83, 83'] verbunden ist. 

8. [202020106717](#) MODULARROBOTER-GELENK UND ZUGEHÖRIGE ABSCHIRMSTRUKTUR FÜR EIN MOTOR- MAGNETFELD DE - 14.01.2021

Int.Class [B25J 17/00](#) Appl.No 202020106717 Applicant Agile Robots AG Inventor

Modularroboter-Gelenk, das einen Motor, ein Untersetzungsgetriebe, eine Hohlwelle [18], einen Ausgangsflansch [1], eine Bremse [14] und einen Geber umfasst, wobei die Hohlwelle am Ausgangsflansch befestigt ist, und der Motor über ein Untersetzungsgetriebe ein Drehmoment an den Ausgangsflansch abgibt, und der Geber einen Hochgeschwindigkeits-Geber und einen Niedergeschwindigkeits-Geber umfasst, wobei der Hochgeschwindigkeits-Geber dazu dient, die Drehgeschwindigkeit des Motoreingangs zu erfassen und der Niedergeschwindigkeits-Geber verwendet wird, um die Geschwindigkeit der Hohlwelle zu ermitteln, dadurch gekennzeichnet, dass der Hochgeschwindigkeits-Geber und der Niedergeschwindigkeits-Geber beide auf einer Seite des Motors angeordnet sind, der Hochgeschwindigkeits-Geber einen Lesekopf [12] der Hochgeschwindigkeits-Seite und einen Magnetring [13] der Hochgeschwindigkeits-Seite umfasst, wobei der Lesekopf [12] der Hochgeschwindigkeitsseite auf einer Seite der Lesekopf-Halterung [11] der Hochgeschwindigkeits-Seite gegenüberliegend angeordnet sind, und dass das modulare Robotergelenk eine Magnetfeld-Abschirmplatte [29] aufweist, die auf der Seite der Lesekopf-Halterung [11] in der Nähe des Motors angeordnet ist. 

9. [WO/2021/104949](#) CABLE GUIDED STRUCTURE AND MODULAR ROBOT WITH THE SAME WO - 03.06.2021

Int.Class [B25J 19/00](#) Appl.No PCT/EP2020/082433 Applicant AGILE ROBOTS AG Inventor CHEN, Zhaopeng

The invention discloses a cable guided structure comprising a threading portion, a guiding portion, and a mounting portion; wherein, the threading portion includes a threading hole surrounding wall, and a threading hole is formed in the threading hole surrounding wall, and the cable can be passed through the threading hole; the guiding portion forms into a long structure, and is used to guide the cable; the mounting portion is used to fix the cable guided structure to other components. The cable guided structure of the present invention can fix the cables in the narrow space of the robot arm, and prevents the cable from rubbing against other components, and also prevent the cables from moving or abrasion during moving of the robot arm.

10. [202247030721](#) CABLE GUIDED STRUCTURE AND MODULAR ROBOT WITH THE SAME IN - 03.06.2022

Int.Class [H02G/](#) Appl.No 202247030721 Applicant AGILE ROBOTS AG Inventor CHEN, Zhaopeng

The invention discloses a cable guided structure comprising a threading portion, a guiding portion, and a mounting portion; wherein, the threading portion includes a threading hole surrounding wall, and a threading hole is formed in the threading hole surrounding wall, and the cable can be passed through the threading hole; the guiding portion forms into a long structure, and is used to guide the cable; the mounting portion is used to fix the cable guided structure to other components. The cable guided structure of the present invention can fix the cables in the narrow space of the robot arm, and prevents the cable from rubbing against other components, and also prevent the cables from moving or abrasion during moving of the robot arm.