

ALLNAMES:("OnRobot A/S")

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Machine translation

1. [WO/2022/048719](#) CHANGING STATION, METHOD FOR CHANGING SANDPAPER AND ROBOT SYSTEM

WO - 10.03.2022

Int.Class [B25J 11/00](#) Appl.No PCT/DK2021/050266 Applicant ONROBOT A/S Inventor TAR, Ákos

A method for automatically attaching a surface treatment media [24] to a surface treatment tool [26] mounted on a robot arm [28] of a robot [30] having an articulated robot arm [28] is disclosed. The surface treatment tool [26] comprises a head [40] configured to receive the surface treatment media [24]. The method comprises the step of placing the head [40] on a surface [8] and applying a predefined force [Fi] to press the head [40] towards the surface [8] when no surface treatment media [24] has been attached to the head [40]. The method comprises the following steps: -measuring the distance between the head [40] and the surface [8] by means of one or more positioning sensors of the robot arm [28] or the surface treatment tool [26]; -attaching a surface treatment media [24] to the head [40] and placing the head [40] on the surface [8] when the surface treatment media [24] is attached to the head [40] and -measuring the distance between the head [40] and the surface [8] by means of the one or more positioning sensors of the robot arm [28] or the surface treatment tool [26] when the surface treatment media [24] is attached to the head [40] and.

2. [WO/2022/122106](#) DISPENSER TOOL AND ROBOT WITH SUCH TOOL

WO - 16.06.2022

Int.Class [B05C 17/005](#) Appl.No PCT/DK2021/050362 Applicant ONROBOT A/S Inventor ALI SAOUD, Hicham

A front-loaded dispenser tool [1] for dispensing viscous paste construction material from a cartridge [8] and an automated robot [21] for the tool [1]. A pair of arms [7A, 7B] on opposite sides of an insertion opening [6A] for the cartridge [8] are arranged rotationally for reducing the size of the opening [6A] by the rotation and thereby locking the cartridge [8] inside the tool [1].

3. [WO/2021/245136](#) SYSTEMS AND METHODS FOR MAGNETIC GRIPPING

WO - 09.12.2021

Int.Class [B25J 15/06](#) Appl.No PCT/EP2021/064792 Applicant ONROBOT A/S Inventor MCAULEY, Jason

Provided herein are systems and methods for magnetically gripping an object. A magnetic gripping system may comprise a gripper having different, tunable gripping states that are associated with different magnetic field strengths.

4. [3150722](#) DUAL ELECTRODE ELECTROADHESION AND DUST MITIGATION/CLEANING SYSTEM

CA - 18.03.2021

Int.Class [C09J 7/00](#) Appl.No 3150722 Applicant ONROBOT A/S Inventor WETTELS, NICHOLAS

Systems and methods are provided for an electroactuated adhesion system containing a dry adhesive material and at least two patterned electrodes. The two or more patterned electrodes may be capable of promoting or increasing adhesion of the electroactuated adhesion system while simultaneously preventing or mitigating the accumulation of dust, contaminants, or particulates on the surface of the adhesive material.

5. [WO/2021/048000](#) DUAL ELECTRODE ELECTROADHESION AND DUST MITIGATION/CLEANING SYSTEM

WO - 18.03.2021

Int.Class [C09J 7/00](#) Appl.No PCT/EP2020/074673 Applicant ONROBOT A/S Inventor WETTELS, Nicholas

Systems and methods are provided for an electroactuated adhesion system containing a dry adhesive material and at least two patterned electrodes. The two or more patterned electrodes may be capable of promoting or increasing adhesion of the electroactuated adhesion system while simultaneously preventing or mitigating the accumulation of dust, contaminants, or particulates on the surface of the adhesive material.

6. [WO/2020/015802](#) SAFE COLLABORATIVE GRIPPING DEVICE

WO - 23.01.2020

Int.Class [B25J 9/16](#) Appl.No PCT/DK2019/050224 Applicant ONROBOT A/S Inventor KIEFFER, Lasse

A method for controlling a gripping device [2] for a robot [20] comprising two or more gripping structures [4, 4'] movably arranged relative to each other and being configured to grip an object [8, 16] is disclosed. The method comprises the step of actively restricting the displacement [ΔD] of at least one of the two or more gripping structures [4, 4'] so that said displacement [ΔD] is less than or equal to a predefined maximum displacement [ΔDmax]. The method comprises the step of: a) detecting when at least one of gripping structures [4, 4'] is in contact with the object [8, 16] and b) increasing the force [F] exerted by at least one of the two or more gripping structures [4, 4'] to the object [8, 16] from a predefined first level [F1] to a predefined second level [F2] when it has been detected that at least one of the two or more gripping structures [4, 4'] is in contact with the object [8, 16]

7. [3105908](#) SAFE COLLABORATIVE GRIPPING DEVICE

CA - 23.01.2020

Int.Class [B25J 9/16](#) Appl.No 3105908 Applicant ONROBOT A/S Inventor KIEFFER, LASSE

A method for controlling a gripping device [2] for a robot [20] comprising two or more gripping structures [4, 4'] movably arranged relative to each other and being configured to grip an object [8, 16] is disclosed. The method comprises the step of actively restricting the displacement [ΔD] of at least one of the two or more gripping structures [4, 4'] so that said displacement [ΔD] is less than or equal to a predefined maximum displacement [ΔDmax]. The method comprises the step of: a) detecting when at least one of gripping structures [4, 4'] is in contact with the object [8, 16] and b) increasing the force [F] exerted

by at least one of the two or more gripping structures [4, 4'] to the object [8, 18] from a predefined first level [F₁] to a predefined second level [F₂] when it has been detected that at least one of the two or more gripping structures [4, 4'] is in contact with the object [8, 16]

8. [20210146534](#) SAFE COLLABORATIVE GRIPPING DEVICE

US - 20.05.2021

Int.Class [B25J 9/16](#) Appl.No 17147666 Applicant OnRobot A/S Inventor Lasse Kieffer

A method for controlling a gripping device [2] for a robot [20] comprising two or more gripping structures [4, 4'] movably arranged relative to each other and being configured to grip an object [8, 16] is disclosed. The method comprises actively restricting the displacement [ΔD] of at least one of the two or more gripping structures so that said displacement is less than or equal to a predefined maximum displacement [ΔD_{max}]. The method comprises the steps of detecting when at least one of the gripping structures is in contact with the object and increasing the force [F] exerted by at least one of the two or more gripping structures to the object from a predefined first level [F₁] to a predefined second level [F₂] when it has been detected that at least one of the two or more gripping structures is in contact with the object.

9. [20200306996](#) EASY COLLABORATIVE TOOL CHANGER

US - 01.10.2020

Int.Class [B25J 15/04](#) Appl.No 16901394 Applicant ONROBOT A/S Inventor Lasse KIEFFER

A connector [70] for mechanically connecting a device [2] to a robot [20], wherein the connector [70] comprises a first portion [74] configured to be attached to the robot [20] and a second portion [76] configured to be attached to a device [2] configured to be connected to the robot [20]. The first portion [74] and the second portion [76] are detachably attached to each other by means of:

- a) a first connection portion [1] constituting a rotational system comprising a pivot [116] about which the first portion [74] can rotate with respect to the second portion [76] and
- b) a second connection portion [1'] constituting a mechanical locking structure that prevents the first portion [74] and the second portion [76] from being detached from each other.

10. [20210162610](#) GRIPPING DEVICE

US - 03.06.2021

Int.Class [B25J 15/04](#) Appl.No 16900911 Applicant ONROBOT A/S Inventor Lasse Kieffer

A gripping device [2] configured to be detachably attached to a robot [20]. The gripping device [2] comprises one or more extremities [10, 10'] provided with one or more suction members [12, 12'] connected to a vacuum source [18]. At least two of the extremities [10, 10'] are rotatably arranged with respect to each other.

11. [WO/2019/114893](#) GRIPPING DEVICE

WO - 20.06.2019

Int.Class [B25J 15/00](#) Appl.No PCT/DK2018/050287 Applicant ONROBOT A/S Inventor KIEFFER, Lasse

A gripping device [2] configured to be detachably attached to a robot [20]. The gripping device [2] comprises one or more extremities [10, 0'] provided with one or more suction members [12, 12'] connected to a vacuum source [18]. At least two of the extremities [10, 10'] are rotatably arranged with respect to each other.

12. [WO/2019/114895](#) EASY COLLABORATIVE TOOL CHANGER

WO - 20.06.2019

Int.Class [B25J 15/00](#) Appl.No PCT/DK2018/050292 Applicant ONROBOT A/S Inventor KIEFFER, Lasse

A connector [70] for mechanically connecting a device [2] to a robot [20], wherein the connector [70] comprises a first portion [74] configured to be attached to the robot [20] and a second portion [76] configured to be attached to a device [2] configured to be connected to the robot [20]. The first portion [74] and the second portion [76] are detachably attached to each other by means of: a) a first connection portion [1] constituting a rotational system comprising a pivot [116] about which the first portion [74] can rotate with respect to the second portion [76] and b) a second connection portion [1'] constituting a mechanical locking structure that prevents the first portion [74] and the second portion [76] from being detached from each other.

13. [3084685](#) EASY COLLABORATIVE TOOL CHANGER

CA - 20.06.2019

Int.Class [B25J 15/00](#) Appl.No 3084685 Applicant ONROBOT A/S Inventor

A connector [70] for mechanically connecting a device [2] to a robot [20], wherein the connector [70] comprises a first portion [74] configured to be attached to the robot [20] and a second portion [76] configured to be attached to a device [2] configured to be connected to the robot [20]. The first portion [74] and the second portion [76] are detachably attached to each other by means of: a) a first connection portion [1] constituting a rotational system comprising a pivot [116] about which the first portion [74] can rotate with respect to the second portion [76] and b) a second connection portion [1'] constituting a mechanical locking structure that prevents the first portion [74] and the second portion [76] from being detached from each other.

14. [20200209085](#) SYSTEMS, DEVICES, AND METHODS FOR SENSING LOCATIONS AND FORCES

US - 02.07.2020

Int.Class [G01L 5/22](#) Appl.No 16700024 Applicant ONROBOT LOS ANGELES INC. Inventor Nicholas Wettels

Provided are systems, devices, and methods for sensing location and forces. A robotic effector comprising a skin and a core can have a plurality of electrodes integrated in the skin and/or core. Upon interaction with a target object, the robotic effector may determine a total force and/or a location of the force by the target object on the robotic effector. Sensitivity and dynamic range of the robotic effector may improve by changing various configurations.

