

ALLNAMES:(ELITE Robot Co., Ltd.)

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Machine translation

1. **214025709** VISUAL INDUSTRIAL ROBOT SIMULATION SYSTEM

CN - 24.08.2021

Int.Class **B25J 9/00** Appl.No 202022635212.0 Applicant SUZHOU ELITE ROBOT CO., LTD. Inventor SUN KAI

The utility model relates to a visual industrial robot simulation system, the industrial robot system comprises an industrial robot and an operation device, the operation device comprises a display part used for displaying robot simulation images and a first pose sensor and/or a first orientation sensor used for detecting the pose of the operation device; the industrial robot comprises an obtaining module used for obtaining the installation pose of the industrial robot; the industrial robot system comprises a control module which is used for adjusting the simulation image of the display part according to the change of at least one of the installation posture of the robot and the posture of the operation equipment, so that the visual angle of the simulation image displayed by the display part is consistent with that of the industrial robot. The industrial robot teaching demonstration device has the advantages that teaching of an industrial robot is more visual, and operation convenience is good.

2. **212421307** INDUSTRIAL ROBOT CAPABLE OF IMPROVING SAFETY CONTROL PERFORMANCE

CN - 29.01.2021

Int.Class **B25J 9/16** Appl.No 202021060878.1 Applicant SUZHOU ELITE ROBOT CO., LTD. Inventor SUN KAI

The utility model relates to an industrial robot capable of improving safety control performance. The industrial robot comprises a base; a robot arm; the joints are used for connecting the two adjacent mechanical arm parts; one end of the execution end is connected to the mechanical arm, and the other end can be connected with a tool; the speed or acceleration sensor is arranged on the joint or arranged on the joint and the execution end; the transmission device is arranged on the joint; and the control module is arranged on the joint. A first control module and a second control module of the control module acquire first safety information and second safety information respectively, and control the robot to execute safety actions when the two pieces of safety information are inconsistent. The industrial robot has the advantages of being good in safety and low in cost.

3. **110181546** THREE-FINGER UNDER-ACTUATED DEXTEROUS HAND

CN - 30.08.2019

Int.Class **B25J 15/02** Appl.No 201910523829.2 Applicant SUZHOU ELITE ROBOT CO., LTD. Inventor BAO JIALEI

The invention discloses a three-finger under-actuated dexterous hand. The three-finger under-actuated dexterous hand comprises a base body palm, a direction-fixed three-knuckle finger claw, two symmetrically arranged rotatable three-knuckle finger claws, a motor and a transmission mechanism, wherein the motor and the transmission mechanism control the rotatable finger claws. The three-finger under-actuated dexterous hand can meet the demand for grabbing objects in different shapes and dimensions and has high environment adaptive capacity.

4. **214558851** MOTOR ENCODER AND ROBOT JOINT

CN - 02.11.2021

Int.Class **B23P 19/02** Appl.No 202023143907.3 Applicant SUZHOU ELITE ROBOT CO., LTD. Inventor GAO YUGANG

The utility model relates to a motor encoder and a robot joint, the motor encoder comprises a support, and a rotating assembly, an optical code disc and an optical code disc read head which are installed on the support, the optical code disc is connected with the rotating assembly, the support comprises a boss which extends outwards along the surface, and the boss is connected with the optical code disc read head. The boss is used for installing an optical code disc reading head to one side of the optical code disc, and the rotating assembly comprises a rotating shaft and a bearing. The beneficial effects of the utility model are that the motor encoder is high in modularization degree and good in working stability.

5. **113910232** ADAPTIVE ATTITUDE TRACKING METHOD AND DEVICE, STORAGE MEDIUM AND ELECTRONIC EQUIPMENT

CN - 11.01.2022

Int.Class **B25J 9/16** Appl.No 202111252255.3 Applicant SUZHOU ELITE ROBOT CO., LTD. Inventor XIE SHENGWEN

The invention provides an adaptive attitude tracking method and device, a storage medium and electronic equipment. The method is applied to a robot, and comprises: fusing at least two preset controllers to generate a hybrid controller; determining a position interpolation amount and an initial attitude interpolation amount of the robot according to the hybrid controller, and performing zero clearing on the initial attitude interpolation amount; calculating the attitude interpolation amount of the robot according to the current attitude adaptive change; acquiring a joint space interpolation amount of the robot according to the position interpolation amount and the attitude interpolation amount; and interpolating the current pose of the robot according to the joint space interpolation amount, and controlling the robot to operate based on the interpolated pose. By the adoption of the scheme, the operation difficulty of the robot can be simplified, and the coping capacity of the robot for complex working conditions is improved.

6. **114074326** SAFETY SYSTEM FOR ENSURING POSE BOUNDARY LIMITATION OF ROBOT

CN - 22.02.2022

Int.Class **B25J 9/16** Appl.No 202010816993.5 Applicant SUZHOU ELITE ROBOT CO., LTD. Inventor SUN KAI

The invention relates to a safety system for ensuring pose boundary limitation of a robot. The safety system comprises: an industrial robot and a safety control system, wherein the safety control system comprising an acquisition module for acquiring a current position of the robot and robot pose boundary information, a calculation module which is used for calculating the safe distance from the current position to the pose boundary and calculating a necessary braking torque/braking force for braking of the robot within the safe distance based on the safe distance, and a control module which is used for judging whether the maximum braking torque/braking force capable of being provided by the current position of the robot is larger than the necessary braking torque/braking force or not, judging whether the estimated braking distance of the maximum braking torque and/or braking force capable of being provided

by the robot currently is smaller than the safety distance or not, and if at least any one of the judgment is not met, controlling the robot to decelerate or stop. The safety system has the beneficial effect that the safety judgment reliability of the industrial robot system is high.

7. **210850321** DEFORMABLE SUCTION CUP SET CAPABLE OF GRABBING OBJECTS OF MULTIPLE SIZES

CN - 26.06.2020

Int.Class **B25J 15/06** Appl.No 201921799758.0 Applicant SUZHOU ELITE ROBOT CO., LTD. Inventor SUN KAI

The utility model discloses a deformable suction cup set capable of grabbing objects of multiple sizes. The deformable suction cup set comprises a base, the sucker frames can be arranged from a horizontal position to a vertical upward position, and the two sucker frames are symmetrically arranged; the sucker frames can be arranged from the horizontal position to the downward 90-degree position, and the two sucker frames are symmetrically arranged. The deformable suction cup set can meet the grabbing requirements of objects of different sizes, and is high in environment adaptability.

8. **210173606** PNEUMATIC SOFT MECHANICAL GRIPPER WITH ADSORPTION DEVICE

CN - 24.03.2020

Int.Class **B25J 15/08** Appl.No 201920547898.2 Applicant SUZHOU ELITE ROBOT CO., LTD. Inventor LI XUE

The utility model discloses a pneumatic soft mechanical gripper with an adsorption device. The manipulator comprises a main body bracket, a vacuum adsorption part and a pneumatic grabbing part, the vacuum adsorption part comprises a vacuum air cylinder and a vacuum suction cup, the pneumatic grabbing part comprises at least two pneumatic assemblies, and each pneumatic assembly comprises a pneumatic connector, a pneumatic connecting piece, a finger connecting piece and a pneumatic soft finger which are connected in sequence. Objects are grabbed together through adsorption of the vacuum suction cups, stretching and retracting of the vacuum air cylinders and bending of the pneumatic soft fingers, so that the pneumatic soft mechanical gripper can reliably grab fragile and irregular objects in a dense environment, and the grabbing stability and adaptability are improved.

9. **215240859** MODULAR INDUSTRIAL ROBOT CAPABLE OF IDENTIFYING BODY STRUCTURE

CN - 21.12.2021

Int.Class **B25J 9/08** Appl.No 202120591222.0 Applicant SUZHOU ELITE ROBOT CO., LTD. Inventor SUN KAI

The utility model relates to a modular industrial robot capable of identifying a body structure, the modular industrial robot comprises a plurality of robot modules and a control module, the plurality of robot modules are detachably connected into a whole, the plurality of robot modules comprise at least three different types of robot modules, each robot module comprises a feature unit, feature parameters representing feature information of the robot modules are stored in the feature units, and the control module is electrically connected to the robot modules and used for recognizing the feature parameters of the robot modules and controlling operation of the robot according to the feature parameters. The industrial robot has the beneficial effects that each module of the industrial robot can be adaptively replaced, and the industrial robot is high in modularization degree and high in use flexibility.

10. **215240871** ROBOT CAPABLE OF QUICKLY CORRECTING PRECISION ACCORDING TO TEACHING POINTS

CN - 21.12.2021

Int.Class **B25J 9/16** Appl.No 202120992378.X Applicant SUZHOU ELITE ROBOT CO., LTD. Inventor SUN KAI

The utility model relates to a robot capable of quickly correcting precision according to teaching points, which comprises a loading module for loading a robot teaching program before the robot is replaced, and the teaching program stores robot coordinates of each teaching point; the sampling module is used for selecting part of teaching points as positioning points according to the teaching program, acquiring robot coordinates of the positioning points in the teaching program and defining the robot coordinates as original robot coordinates; the teaching module is used for teaching the robot to each positioning point, obtaining robot coordinates again and defining the robot coordinates as new robot coordinates; and the calibration module is used for calibrating the robot according to the new robot coordinate and the original robot coordinate system and acquiring parameter compensation information of the robot. And the compensation module corrects the robot parameters according to the parameter compensation information and controls the robot to operate according to the parameters. The beneficial effects of the utility model are that the correction of the robot is simple and easy to realize, and the relative precision of the robot before and after the replacement of the robot is better.

