

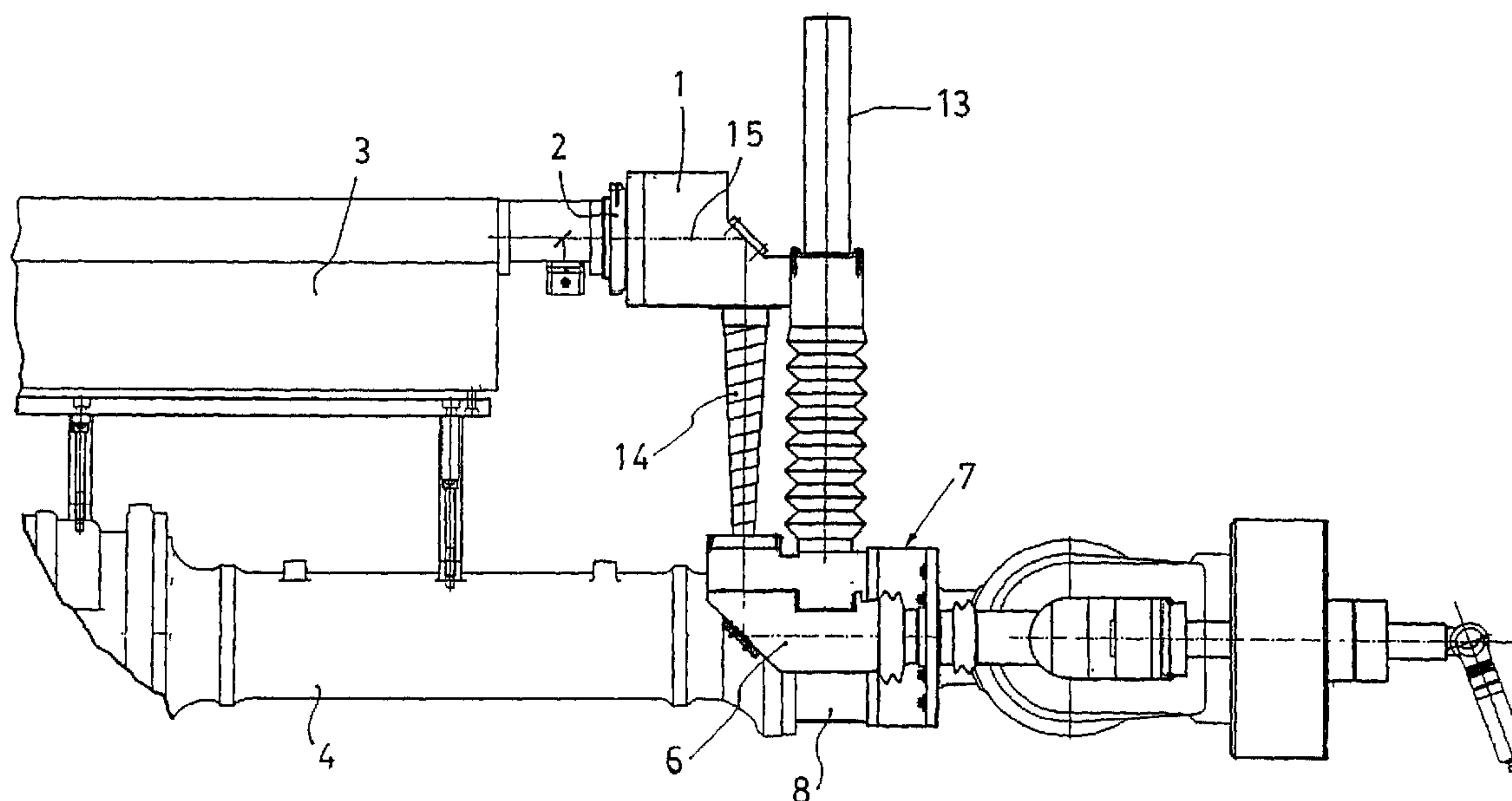


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(54) Titre : BRAS OPTIQUE DESTINE A DES ROBOTS

(54) Title: OPTICAL ARM FOR GUIDING A LASER BEAM ON A ROBOT ARM



(57) Abrégé/Abstract:

This optical arm applicable to robots is comprised of: some bent tubular parts (1, 6, 16, 18), a straight tubular length (21) and an outlet part (23), coupled together with the possibility of rotation; also including some means (7) to secure the optical arm to a robot (5). The bent tubular part (1) is mounted with the possibility of rotation on the outlet (2) of a laser generator (3) secured to the third arm (4) of the robot (5). Parts (1, 6, 16 and 18) have a window (28), in each bend, equipped with some inner lugs (28) which a mirror (29) is pressed on to by means of some springs (33) foreseen with a removable part (32).

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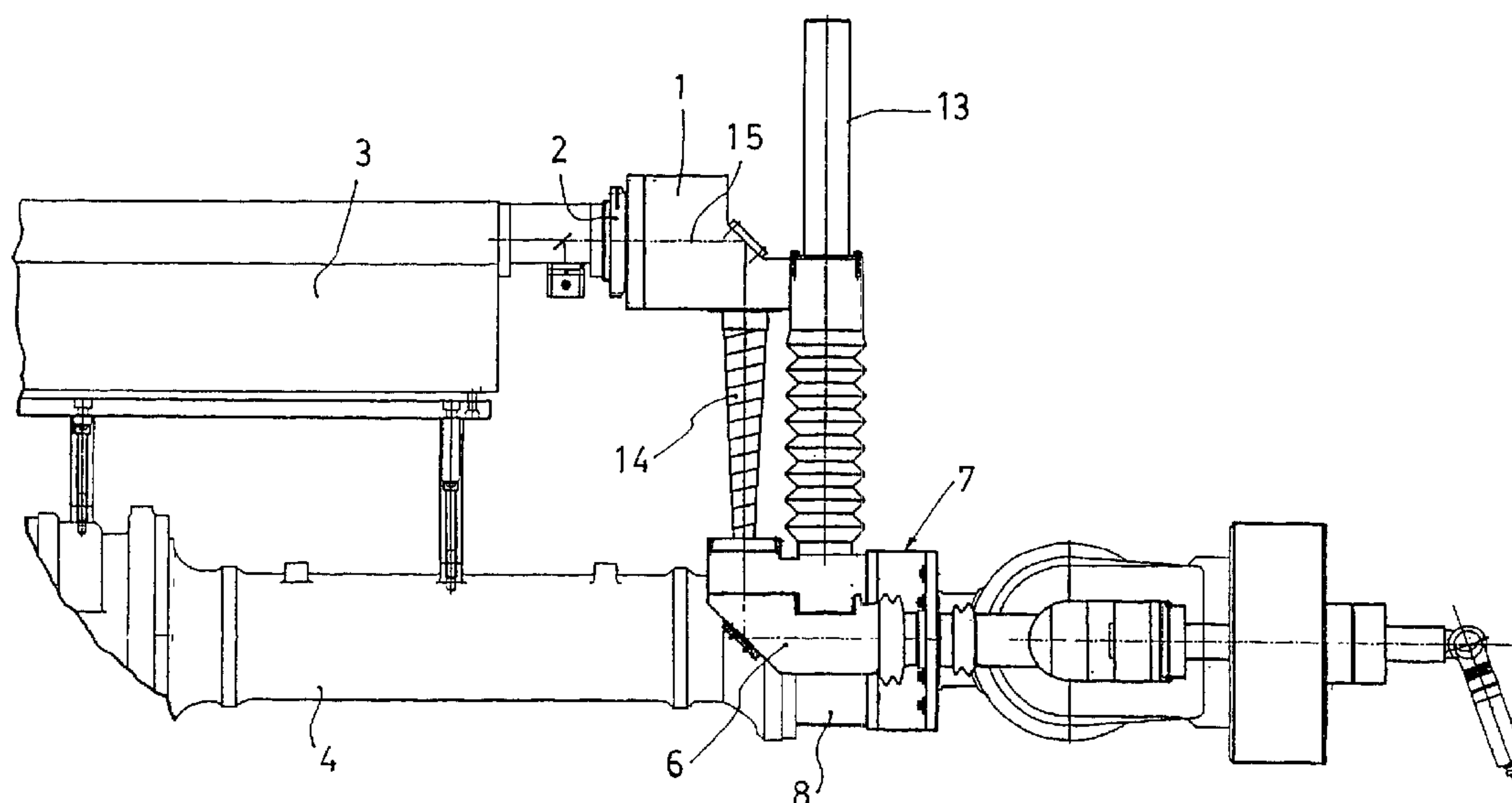
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(54) Title: OPTICAL ARM FOR GUIDING A LASER BEAM ON A ROBOT ARM



(57) Abstract: This optical arm applicable to robots is comprised of: some bent tubular parts (1, 6, 16, 18), a straight tubular length (21) and an outlet part (23), coupled together with the possibility of rotation; also including some means (7) to secure the optical arm to a robot (5). The bent tubular part (1) is mounted with the possibility of rotation on the outlet (2) of a laser generator (3) secured to the third arm (4) of the robot (5). Parts (1, 6, 16 and 18) have a window (28), in each bend, equipped with some inner lugs (28) which a mirror (29) is pressed on to by means of some springs (33) foreseen with a removable part (32).

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DESCRIPTION**OPTICAL ARM APPLICABLE TO ROBOTS.**

5 OBJECT OF THE INVENTION

This invention refers to an optical arm designed to be coupled to a robot and to adapt to the robot's movements ensuring the guidance of a beam of light from a laser
10 generator to an outlet part.

BACKGROUND OF THE INVENTION.

Currently the use of laser in different applications is
15 normal practice, as well as the use of robots to guide the beam of light in the desired direction.

The use of a laser combined with a robot poses some important problems concerning the guiding of the beam of
20 light from the laser generator to a outlet part or applicator, as the optical arm used to guide it must be able to accompany the robot in its movements.

To achieve this, some of the currently used optical arms
25 are comprised of a series of tubular lengths which are placed parallel to each of the robot arms and which are joined together by means of some articulations, whose rotation axes coincide with each one of the rotation axes of the robot, these articulations including a mirror
30 responsible for making a change in direction of the beam of light, which passes through the inside of the optical arm in each one of these articulations.

These optical arms, apart from been excessively
35 complicated, limit the robot movements to a large extent.

In other cases the laser generator is placed in an area close to the robot, using an optical arm with long stretches and the necessary articulations so that the end part of the optical arm, mounted on the sixth arm of the robot, is able to following the movements of the latter. In this case the optical arm hangs from some supports that considerably stand out from the robot, limiting its movements as well as its area of action to a great extent.

10 DESCRIPTION OF THE INVENTION

To solve the problems mentioned, an optical arm applicable to robots targeted by this invention has been designed and which has some constructive peculiarities aimed at permitting its assembly on any traditional robot, occupying minimum space and practically without limiting the mobility of the robot.

According to this invention, this optical arm is comprised of:

- a first bent tubular part mounted with the possibility of rotation on the outlet from the laser generator secured to the third arm of the robot,
- a second bent tubular part mounted with the possibility of rotation on some support means secured to the fourth arm of the robot,
- some guides that fasten the two bent tubular parts mentioned above, permitting their relative movement and ensuring the permanence of the respective outlets and inlets in opposing positions during the rotation of the fourth arm of the robot,
- an extending tubular element that joins the outlets and the inlets of the aforementioned tubular parts delimiting the passage area of the beam;
- a third bent tubular part, which is secured to the second bent part, its inlet being placed opposite the

- outlet of this second bent part and its outlet placed coaxially with the fifth rotation axis of the robot;
- a tubular part with three consecutive bends, the inlet being mounted coaxially, with possibility of rotation, on the outlet of the third bent part and with its outlet placed parallel to the sixth rotation axis of the robot;
 - some means to fasten the part equipped with three consecutive bends to the fifth arm of the robot, permitting its rotation around the outlet of the their bent part,
 - a straight tubular length mounted coaxially on the outlet of the part with three consecutive bends,
 - a support for fastening the tubular length, respect to the fifth arm of the robot, without possibility of rotation,
 - an outlet part mounted coaxially, with possibility of rotation, on the tubular length and
 - some means to transmit the rotation movement of the sixth arm of the robot to the outlet part.

20

In accordance with the invention the outlets of the bent parts will form 90° angles, and these parts have a window in each one of their bends with inner lugs, which defines an inclining plane to support a mirror responsible for causing a change in direction of 90° in the beam of light that falls upon it.

During the construction of the robot the outer surfaces of the lugs mentioned can be reduced as necessary to guarantee that the plane defined by them forms a 45° angle with the beam of light that falls upon the mirror mounted upon them, ensuring that the change in direction of the beam caused by the mirror mentioned is 90° .

35 In accordance with the invention, the parts foreseen with bends have means on the outside to fasten a part provided

with some springs that press the mirror against the support lugs defined in the relative window. The fastening of the mirror respect to these parts by means of the pressure of the springs guarantees the immobilisation
5 of the mirror during the use of the optical arm and facilitates its replacement in the case of deterioration, as to carry out this replacement it will suffice to support the new mirror on the support lugs and again mount the spring-bearing part, without having to make any
10 adjustment in the mirror.

The support means of the optical arm with respect to the spring include a piece of elastic material responsible for absorbing any possible disalignments of the arm respect to
15 the robot during its movements.

The guides mentioned above and responsible for connecting the two bent tubular parts are joined to one of these parts and are mounted with the possibility of longitudinal
20 movement respect to the other, so that during the rotation of the fourth axis of the robot the outlets and inlets of these parts will be kept perfectly aligned.

The means responsible for transmitting the rotation
25 movement of the sixth arm of the robot to the outlet part are comprised of pinions of the same diameter, geared together and secured coaxially to the sixth arm of the robot and to the outlet part, respectively.

30 DESCRIPTION OF THE FIGURES

To complement the description that is being carried out and in order to facilitate the understanding of the characteristics of the invention, a set of drawings are
35 enclosed with this descriptive report where, with an illustrative but limiting nature, the following has been

illustrated:

5 - Figure 1 shows a general profile view of the optical arm targeted by the invention mounted on a traditional six-axis robot.

10 - Figure 2 corresponds to an enlargement of one portion of the previous figure where the optical arm can be seen on a larger scale and where only one part of the robot has been illustrated.

- Figure 3 shows a schematic section of an initial length of the optical arm partially sectioned.

15 - Figure 4 corresponds to a front view of the previous figure where the guides that join the first and second bent tubular parts can be seen.

20 - Figure 5 shows an upper ground plan view of the optical arm partially sectioned and where the means used to transmit the rotation of the sixth arm of the robot to the outlet part of the optical arm can be seen. In this figure the guides that join the first two bent parts have been eliminated.

25 - Figure 6 shows a front view of the window defined in any one of the bent parts, being able to observe therein the lugs used to support the mirror whose outline has been illustrated with a broken line.

30 - Figure 7 shows a profile view of one of the parts used to secure the mirror on the support lugs of one of the bent parts, the latter being partially illustrated and sectioned.

35 - Figure 8 shows an execution example of the support means

used to secure the optical arm of the robot, these means being illustrated sectioned.

PREFERENTIAL EXECUTION OF THE INVENTION

5 As can be seen in the figures referred to, the optical arm targeted by this invention has a first bent tubular part (1) mounted with some bearings, and therefore with the possibility of rotation, on the outlet (2) of a laser generator (3) which is fastened to the third arm (4) of a
10 robot referenced in the assembly as (5). The optical arm has a second bent tubular part (6) which is mounted with some bearings and therefore with the possibility of rotation on some support means (7) fastened to the fourth arm (8) of the robot (5).

15

As can be seen in figure 8, the support means referred to in the assembly as (7) include an annular piece (9) of elastic material whose outer area is secured by means of a flange (10) to an arm (11) joined to the fourth arm of the
20 robot and whose inner area is secured with the relative flange (12) to the optical arm.

Therefore, the fastening of the optical arm to the robot is established through the elastic annular piece (9), the
25 deformation of the latter permitting the absorption of any possible disalignments of the optical arm with respect to the robot when it moves.

Parts (1 and 6) are joined by some parallel guides (13)
30 which are joined to part (6) and which are mounted on part (1) with the possibility of longitudinal movement, these parts ensuring the alignment of the outlet of part (1) and of the inlet of part (6) during the rotation of the fourth arm (8) of the robot.

35

An extending tubular element (14) is mounted on the outlet

of part (1) and on the inlet of part (6), which delimits the passage area of the beam of light (15) coming from the generator (3).

5 The optical arm has a third bent tubular piece (16) whose inlet is secured coaxially to the outlet of the part (6), in turn placing the outlet of the bent part (16) coaxially with the fifth rotation axis (17) of the robot (5).

10 A tubular part (18), which has three consecutive bends, is mounted coaxially on the outlet of part (16) by means of bearings, and therefore with the possibility of rotation. The outlet of the tubular part (18) is placed parallel to the sixth rotation axis (19) of the robot.

15

The tubular part (18) is secured to the fifth arm (20) of the robot (5) by some support means (7) similar to those described above and illustrated in figure 8.

20 A tubular length (21), secured by means of a rigid support (22) to the fifth arm (20) of the robot, is mounted coaxially on the outlet of the tubular part (1), without the possibility of rotation.

25 The outlet part (23) of the optical arm is mounted coaxially on the tubular length (21) and with the possibility of rotation.

As can be seen in figure 5, this outlet part (23) is
30 joined to a pinion (24), which is geared with two pinions (25) of the same diameter as the latter and joined to the sixth arm (26) of the robot. The pinions (25) can be outphased angularly to achieve a fine adjustment of the teeth with respect to the teeth of the pinion (24) and to
35 avoid play in the transmission of the rotation movement of the sixth arm (26) of the robot to the outlet part (23).

The aim of the bent parts (1, 6, 16 and 18) is to provoke the changes in direction of the laser beam (15) coming from the generator (3) so that this is correctly guided through the inside of the optical arm until it reaches the
5 outside through the outlet part (23).

To achieve this, these parts have a window (27) in each of their bends, as shown in figures 6 and 7, equipped with some lugs (28) to support a mirror (29) responsible for
10 reflecting the beam (15) with the subsequent change in direction of the beam.

The outer surface of the lugs (28), which the mirror (29) is supported on, will define a plane that forms a 45°
15 angle exactly with the direction of incidence of the beam of the laser (15) ensuring a 90° change in direction of the same.

To achieve this, the outer surface of the lugs (28) can be
20 reduced as necessary during the assembly and verification phase of the optical arm.

This peculiarity permits the rapid replacement of the mirror (2) in the case of deterioration with having to
25 adjust the new mirror.

To immobilise the mirror (29) in the position of use, illustrated in figures 6 and 7, the bent parts have some holes (30) on the outer surface, which a part (32) is
30 mounted on, using some screws (31). This part has some springs (33), which are responsible for pressing the mirror (29) against the support lugs (28).

The aim of these springs is to prevent the part (32) from
35 being able to exercise excessive pressure on the mirror

(29) on establishing the grip of the setscrews (31) of said part.

Once the nature of the invention has been sufficiently
5 described, as well as an example of preferential
execution, for the appropriate purpose, it is noted that
the materials, shape, size and placement of the elements
described can be modified, providing this does not
represent any alteration of the essential characteristics
10 of the invention that are claimed below.

CLAIMS

- 1.- Optical arm applicable to robots of the type designed to be coupled to a robot (5) and to be adapted to the movements of the robot ensuring the guidance of the laser beam from a generator (3) to an outlet part (23); characterised because it includes:
- a first bent tubular part (1) mounted with the possibility of rotation on the outlet (2) of a laser generator (3) secured to the third arm (4) of the robot (5),
 - a second bent tubular part (6) mounted with the possibility of rotation to some support means (7) secured to the fourth arm (8) of the robot,
 - some guides (13) that join the two bent tubular parts (1 and 6), permitting the relative movement and ensuring the permanence of the respective inlets and outlets in opposing positions during the rotation of the fourth arm (8) of the robot (5),
 - an extending tubular element (14) that joins the outlets and inlets of the aforementioned tubular parts (1, 6) delimiting the passage area of the beam (15);
 - a third bent tubular part (16) which is secured to the second bent part (6), with its inlet opposite the outlet of this part (6) and its outlet placed coaxially with the fifth rotation axis (17) of the robot (5);
 - a tubular part (18) with three consecutive bends, its inlet being mounted coaxially, with the possibility of rotation, on the outlet of the third bent part (16) and with its outlet placed parallel to the sixth rotation axis (19) of the robot (5);
 - means (7) to secure the tubular part (18) on to the fifth arm (20) of the robot, permitting its rotation around the outlet of the third bent part (16),
 - a straight tubular length (21) mounted coaxially on the outlet of the tubular part (18),

- a support (22) to secure, without the possibility of rotation, the tubular length (21) with respect to the fifth arm (20) of the robot (5),
- an outlet part (23) mounted coaxially, with the possibility of rotation, on the tubular length (21) and
- some means to transmit the rotation movement of the sixth arm (26) from the robot to the outlet part (23).

2.- Optical arm, according to the previous claim, characterised because the bends of the parts (1, 6, 16 and 18) define 90° angles.

3.- Optical arm, according to the previous claims, characterised because parts (1, 6, 16 and 18) have a window (27) in each of the bends, provided with some inner lugs (28), which define an inclining plane to support a mirror (29) in charge of provoking a 90° change in direction in the beam of light (15) which falls upon it.

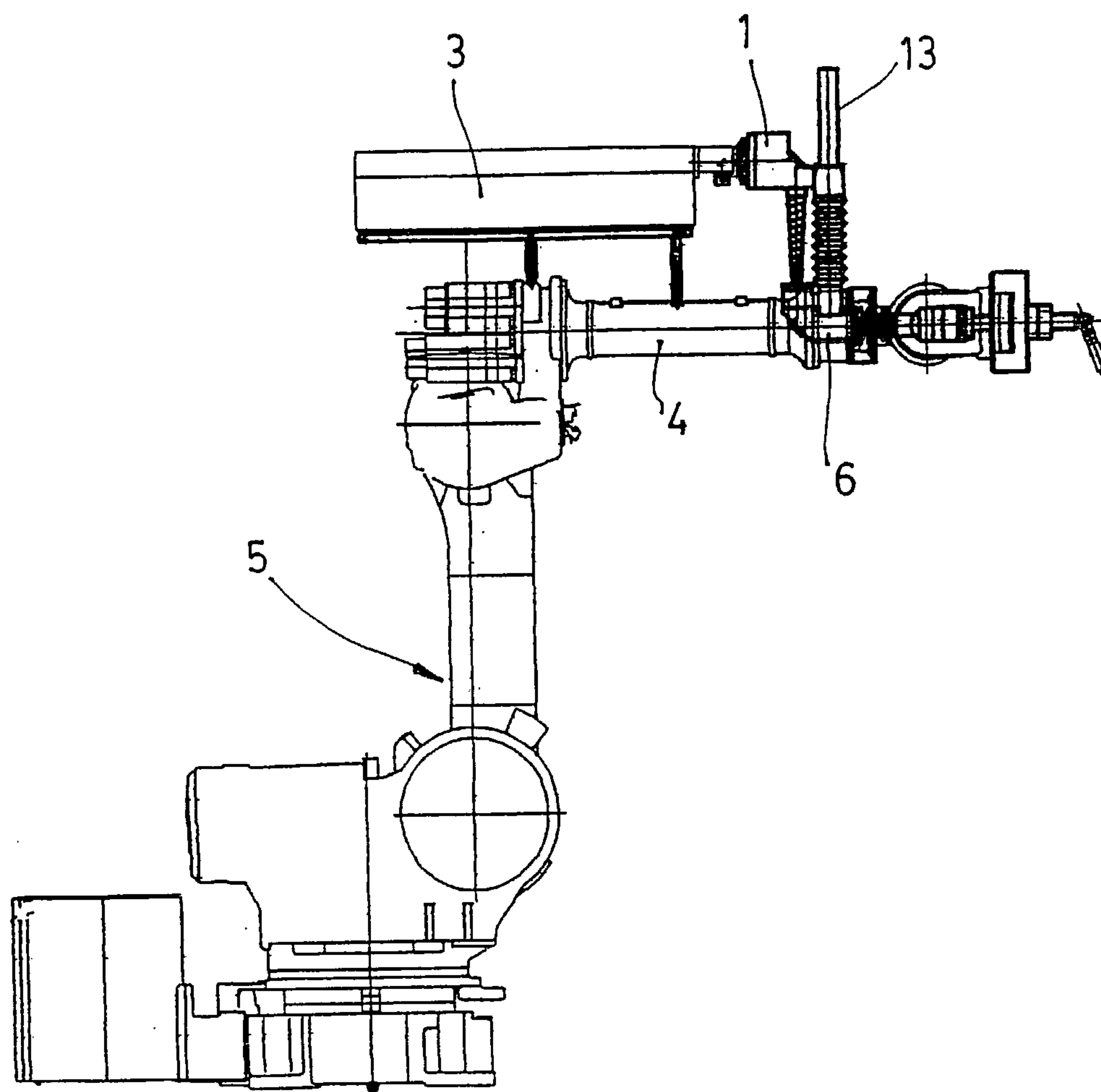
4.- Optical arm, according to the previous claims, characterised because parts (1, 6, 16 and 18) have some means on the outside to secure a part (32) equipped with springs (33) that press the relative mirror (29) against the support lugs (28) defined in the windows (27).

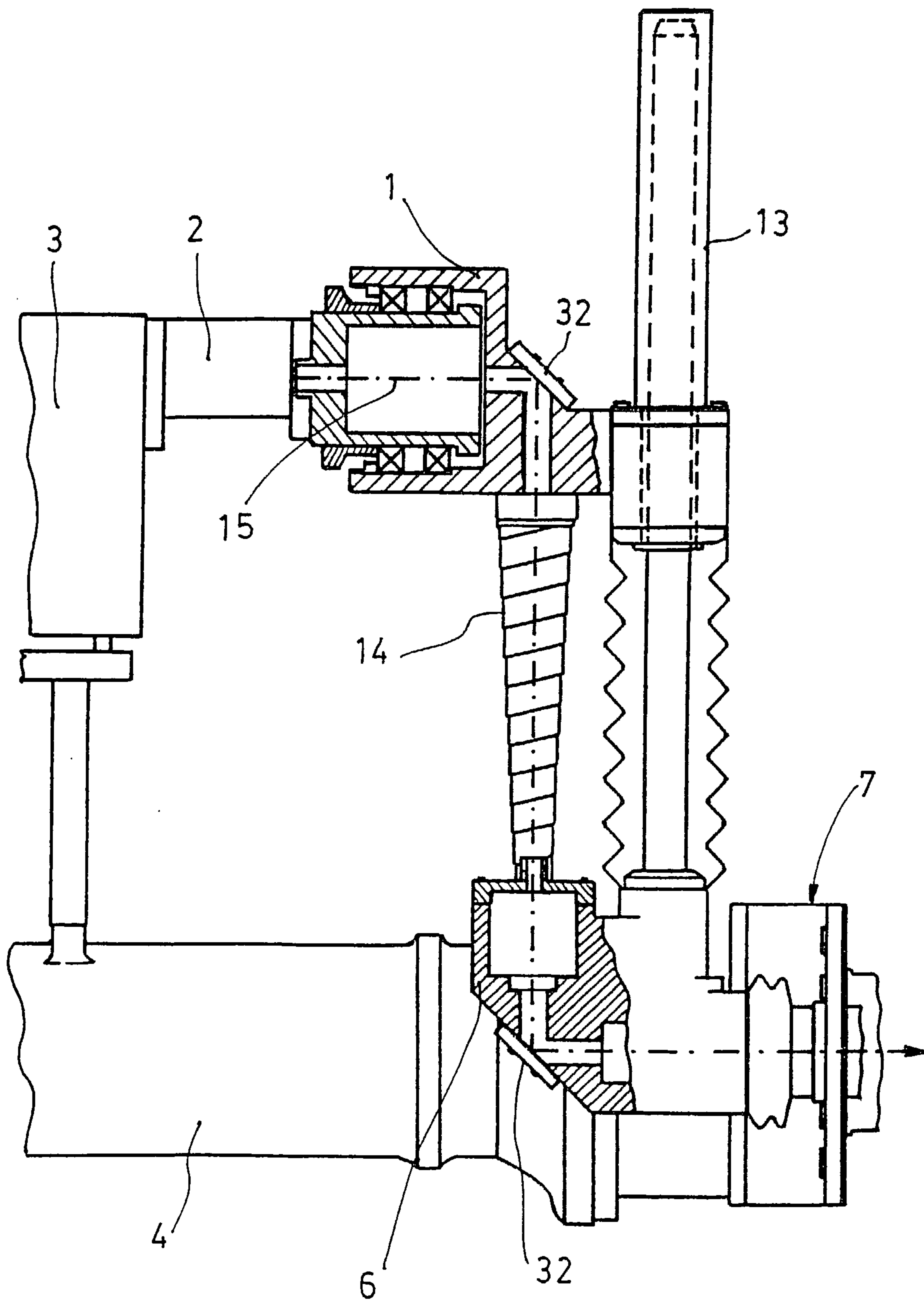
5.- Optical arm, according to the previous claims, characterised because the support means (7) of the optical arm with respect to the robot (5) include a piece of elastic material (9) in charge of absorbing the possible disalignments of the arm with respect to the robot (5) during its movements.

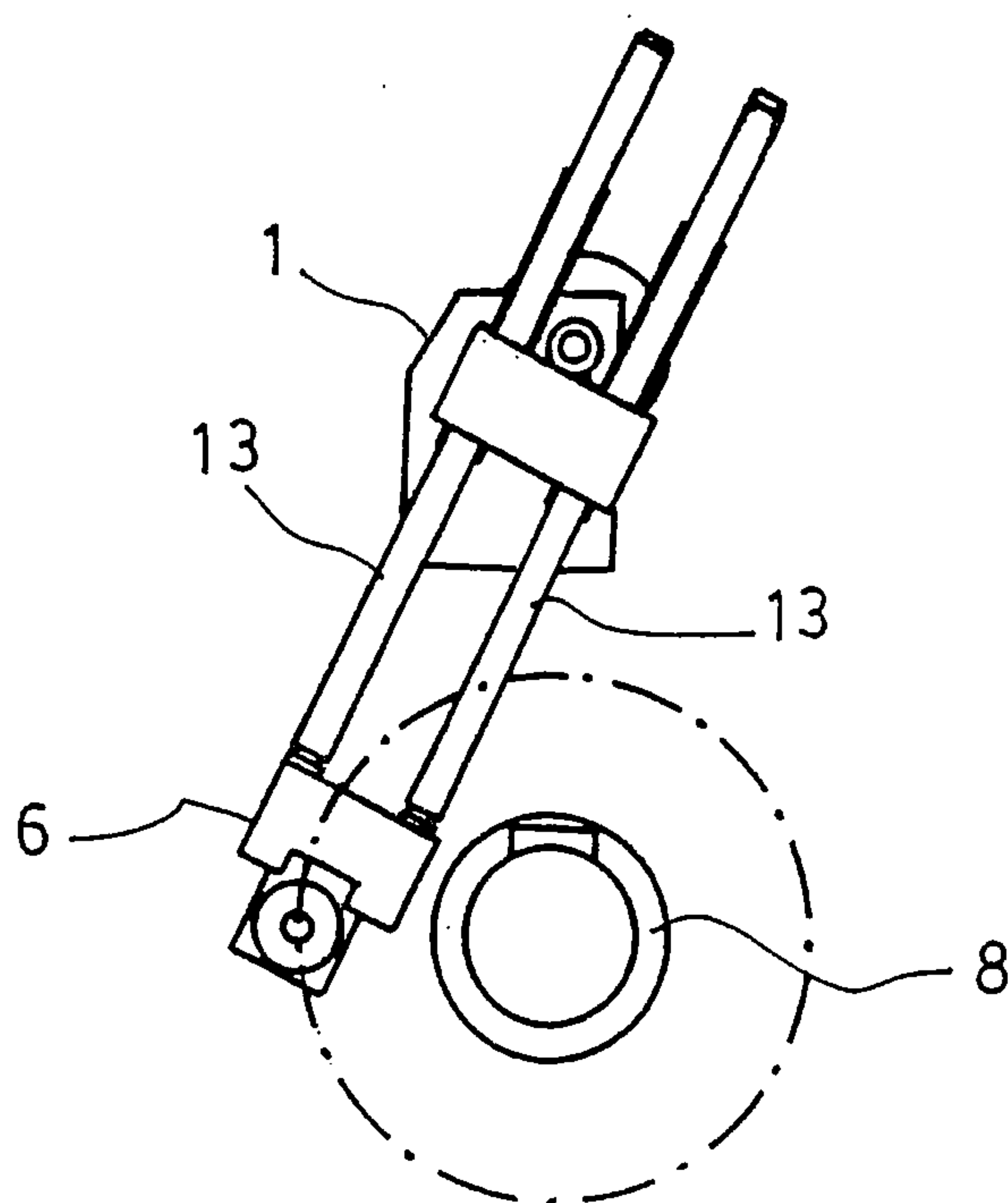
6.- Optical arm, according to the previous claims, characterised because the guides (13) that join the two bent tubular parts (1 and 6) are joined to one of them and are mounted with the possibility of movement with respect

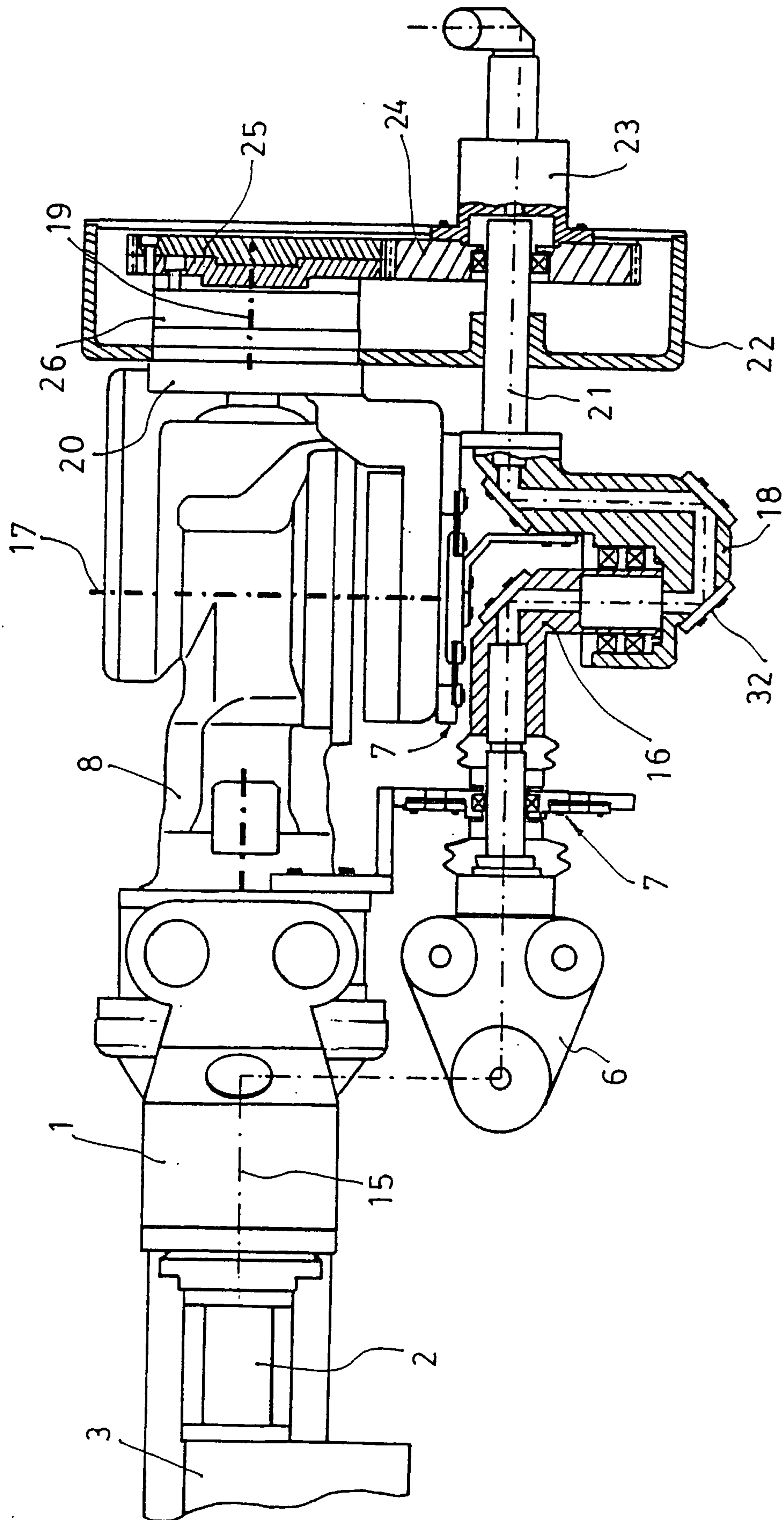
to the other.

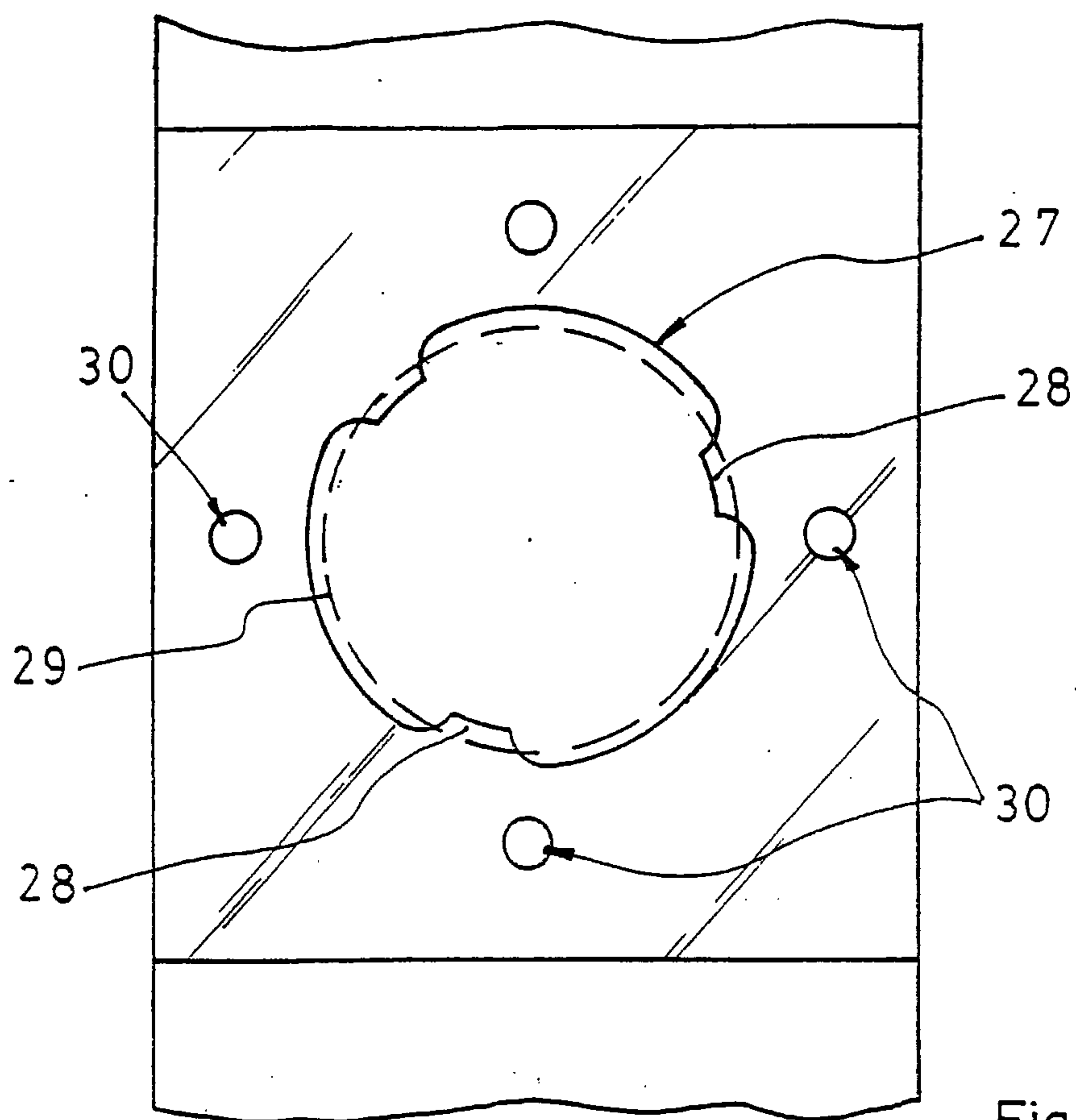
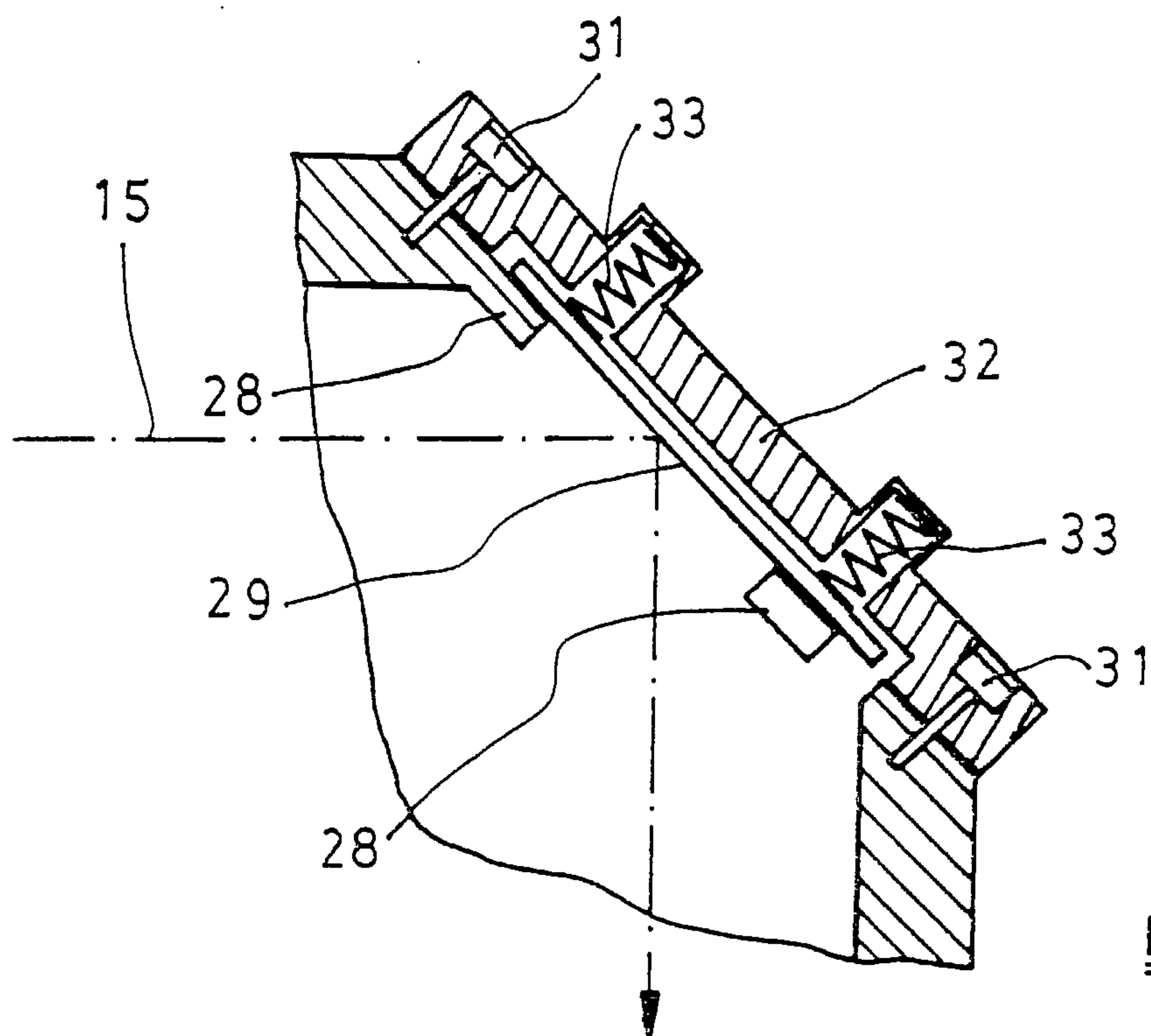
7.- Optical arm, according to the previous claims, characterised because the means responsible for
5 transmitting the rotation movement from the sixth arm (26) of the robot to the outlet part (23) are comprised of some pinions (24 and 25) of the same diameter, geared to each other and secured coaxially to the outlet part (23) and to the sixth arm (26) of the robot respectively.

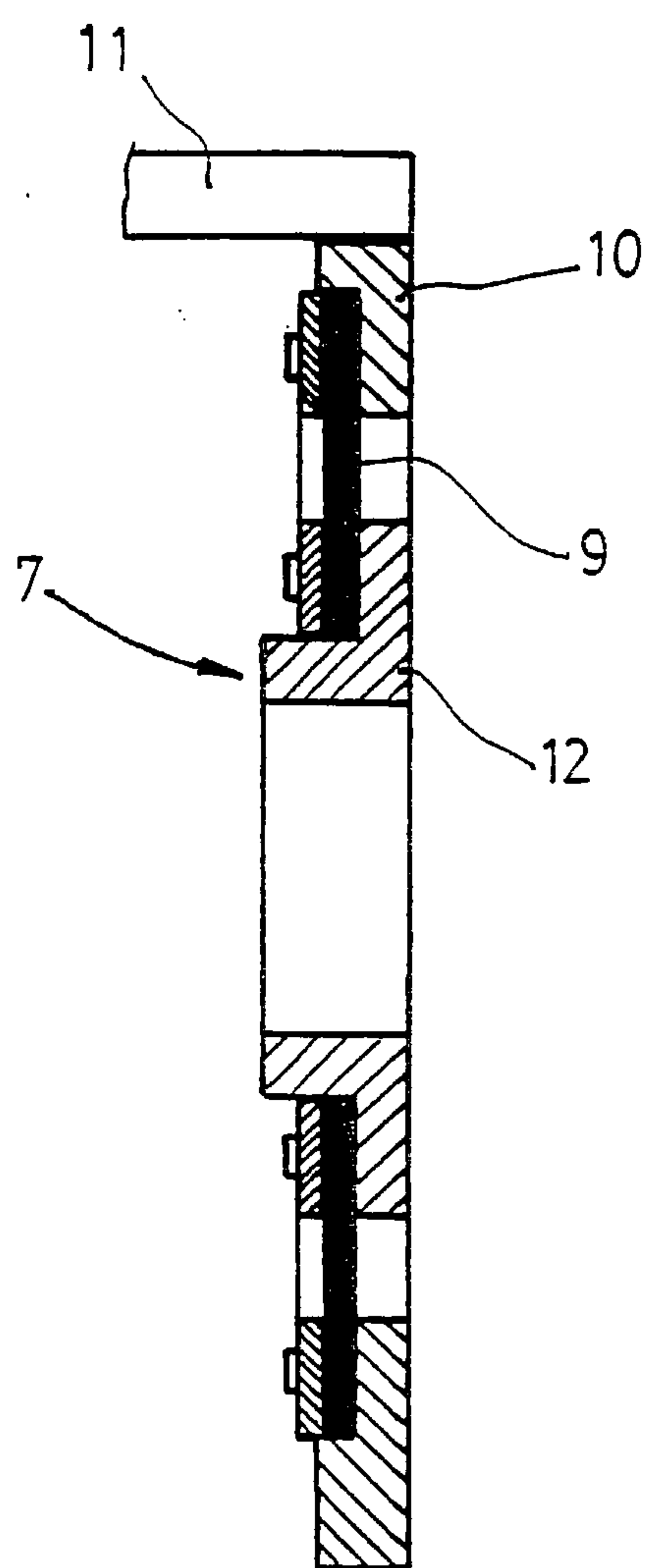
Fig. 1

Fig. 3

Fig.4

Fig. 5

Fig. 6Fig. 7

Fig. 8

