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WO-A1-2005/077789
US-A1- 2003 229 416

DESCRIPTION

[0001] The present invention relates to a bin storage system comprising a three-dimensional bin storage structure and a plurality of robot vehicles which are movable on top of the bin storage structure to retrieve storage bins from the bin storage structure, which bin storage structure comprises: a plurality of pillars which are positioned with internal distances and in a rectangular arrangement adapted to accommodate the storage bins, where the rectangular arrangement of the pillars define storage columns for the storage bins; supporting rails which are arranged in a two-dimensional matrix on top of the pillars and provide a vehicle support for the plurality of robot vehicles allowing each robot vehicle to travel across the bin storage structure in a first direction and in a second direction, which is orthogonal to the first direction; a storage bin delivery station; and a bin lift device which is arranged to receive storage bins from the plurality of robot vehicles and transport the storage bins in a vertical direction from a top level of the bin storage structure to the delivery station, which plurality of robot vehicles each comprises a vehicle body which comprises: a first set of rolling means for moving the robot vehicle along the supporting rails in the first direction; a second set of rolling means for moving the robot vehicle along the supporting rails in the second direction; a cavity for receiving a storage bin; and a lifting device for retrieving a storage bin from a storage column and storing the storage bin in the cavity.

[0002] The invention also relates to a method of operating robot vehicles in such a bin storage structure.

[0003] A remotely operated vehicle for picking up storage bins from a storage system is known. A detailed description of a relevant prior art storage system according to the preamble of claim 1 is given in WO 98/49075. Further, details of a prior art vehicle being suitable for such a storage system is disclosed in Norwegian patent NO317366. More specifically the prior art storage system comprises a three dimensional storage grid containing storage bins that are stacked on top of each other to a certain height. The storage grid is normally constructed as aluminium columns interconnected by top rails. A number of remotely operated vehicles, or robots, are arranged on the top rails. Each vehicle is equipped with a lift for picking up, carrying, and placing bins that are stored inside the storage grid.

[0004] Such a prior art storage system art and prior art robot is illustrated in figures 1 and 2, respectively. The storage system 3 comprises a robot 1 which is arranged to move on dedicated supporting rails 13 and to receive a storage bin 2 from a storage column 8 within a bin storing grid 15. The storage system 3 includes a plurality of such robots 1 and a dedicated bin lift device 50, the latter being arranged to receive a storage bin 2 from the robot 1 at the top level of the bin storing grid 15 and to convey the storage bin 2 down in a vertical direction to a delivery station 60. However, the prior art robot 1 shown in both fig. 1 and fig. 2 suffers from several important disadvantageous during their operation. Firstly, the particular design of the robot prevents access to all off the available storage columns in the storage system. Furthermore, this particular design may cause an undesirable high torque during lifting and

transportation of storage bins, thereby creating potential instability problems, as well as a clear limitation of the robots maximum handling weight. An additional disadvantage caused by the prior art robot design is the fact that only one particular bin and one particular bin height may be accepted for each type of robot in order to ensure adequate stability. Finally, the presence of an integrated yoke / overhang in the upper part of the section receiving the storage bin necessitates an undesired speed reduction at the final stage of the lifting process performed by the yoke suspended vehicle lifting device.

[0005] The object of the present invention is to solve, or at least substantially alleviate, the above-described disadvantageous, that is to provide a vehicle / robot with higher stability properties, higher maximum handling weights, a more effective use of available space during operation and a less time consuming lifting and transporting process of storage bins.

[0006] The above-identified objects are achieved by a bin storage system as defined in claim 1 and a method as defined in claim 8. Further beneficial features are defined in the dependent claims.

[0007] In particular, the present invention concerns a remotely operated vehicle or robot for picking up storage bins from a storage system. The inventive vehicle or robot comprises a vehicle body, which vehicle body further comprises a first section for storing vehicle driving means and a second section for receiving any storage bin stored in a storage column within the storage system, a vehicle lifting device which is at least indirectly connected to the vehicle body in order to lift the storage bin into the second section, a first set of vehicle rolling means connected to the vehicle body in order to allow movement of the vehicle along a first direction (X) within the storage system during use and a second set of vehicle rolling means connected to the vehicle body in order to allow movement of the vehicle along a second direction (Y) in the storage system during use. The second direction (Y) is oriented perpendicular to the first direction (X).

[0008] The inventive vehicle comprises a cavity arranged centrally within the vehicle body. This cavity has at least one bin receiving opening facing towards the underlying storage columns during use. In addition, at least one of the two sets of vehicle rolling means is arranged fully within the vehicle body.

[0009] In order to allow easy entrance of the storage bin into the central cavity, its volume should be larger than the largest storage bin intended to be picked from the storage system. Likewise, the cross sectional area of at least one of the at least one bin receiving opening should be larger than the cross sectional area of the storage bin walls oriented parallel to the cavity opening(s).

[0010] The vehicle may further comprise means for reversibly and selectively displacing either the first set of vehicle rolling means or the second vehicle rolling means away from an underlying vehicle support within the storage system during a change of vehicle direction between the first direction (X) and the second direction (Y).

[0011] Furthermore, in an embodiment the first section may be arranged relative to the second section in such a way that the cross section of the vehicle parallel to the underlying vehicle support deviates from a quadratic shape.

[0012] In a preferred embodiment the vehicle body covers less or equal to the lateral cross sectional area of one central storage column in the first direction (X) and covers the lateral cross sectional area of more than one central storage column in the second direction (Y) during use. In a more specific example the vehicle body extends beyond the lateral cross sectional area of the central storage column at both sides facing the second direction (Y), i.e. covering also some of the cross sectional areas of the adjacent storage columns extending in the second direction (Y). The degree of extension from the central storage column is preferably equal on both of these sides. Central storage column is defined as the storage column which is immediately below a robot when the latter has reached a position allowing pick-up of a storage bin.

[0013] In order to inter alia allow high vehicle stability both sets of vehicle rolling means is preferably arranged symmetrically around the cavity, for example near the lower corners of the vehicle. At least one, and most preferably both, set(s) of vehicle rolling means may comprise at least four wheels. Other embodiments such as the use two perpendicular oriented caterpillar belts may be envisaged. Furthermore, both sets have an exterior design matching a corresponding exterior design on supporting rails constituting the vehicle support in order to provide increased lateral stability when interconnected. Such supporting rails would be arranged in a two dimensional matrix on top of a bin storing structure or grid, where the principal directions of both the matrix and the grid are congruent with the vehicle's first direction (X) and second direction (Y).

[0014] The vehicle may advantageously also include position sensing means to allow measurements of the vehicle position within the storage system during use. This position sensing means may comprise a plurality of position sensors arranged in at least some of the positions on the vehicle body which would transverse the locations of vehicle support where the supporting rails are crossing, for example underneath the vehicle, close to its lower corners.

[0015] The present invention also concerns a storage system which comprises a remotely operated vehicle in accordance with the above mentioned features, a vehicle support comprising a plurality of supporting rails forming a two dimensional matrix of guiding meshes, wherein the vehicle support is configured to guide the movements of the vehicle in the first direction (X) and the second direction (Y) during use, a bin storing structure or grid supporting the vehicle support comprising a plurality of storage columns, wherein each of the storage columns is arranged to accommodate a vertical stack of storage bins and wherein the main part of the bin storing structure coincides with positions on the vehicle support where the supporting rails are crossing, and a bin lift device arranged to convey a vehicle delivered storage bin in a direction perpendicular to the lateral plane of the vehicle support between the

vehicle support and a delivery station.

[0016] In a preferred embodiment at least some of the supporting rails arranged at the outer lateral border areas of the vehicle support form outer guiding meshes having reduced average cross sectional areas compared to the average cross sectional area of the remaining guiding meshes in the vehicle support. For example, the average reduced cross sectional areas of the outer guiding meshes may be about half of the average cross sectional area of the remaining guiding meshes in the vehicle support. In a particularly preferred embodiment these cross sectional areas of the outer guiding meshes are reduced only along the second direction (Y) of the vehicle support.

[0017] The central arrangement of the cavity in the vehicle body relative to the second direction (Y) effectively remove the undesired torque, thereby improving the stability of the robot or vehicle. This arrangement also results in a lifting and transporting process having a weight distribution with a high degree of symmetry. Furthermore, the novel design allows the same vehicle to be used for lifting and transporting storage bins of heights significantly less than the cavity height (i.e. the height extending from the suspension points of the lifting device and to the lower edge of the vehicle) since the framework / body surrounding at least part of the bin receiving cavity effectively hinders any undesired bin reeling / wobbling. The presence of the cavity surrounding body also allows maintaining full or nearly full lifting speed almost all the way to its end position within the cavity, as well as initiation of stable bin transportations towards the delivery station prior to a fully completed bin lifting from a storage column. The protective body around the cavity also gives the possibility of starting a descent of the lifting device event prior to the time the vehicle has come to a final halt above the storage column in question. A significantly higher stability and time efficiency is thus achieved.

[0018] By arranging at least one set of vehicle rolling means fully within the vehicle or robot body additional stability is obtained during the lifting process since the rolling means is situated closer to the storage bin to be lifted. Of the same reason this arrangement reduces the total load on the lifting device. Furthermore, the arrangement is more space efficient relative to the prior art robot illustrated in figure 2 since the roller means does not give any additional extensions in at least one of the two robots moving directions (X and Y). Production of smaller sized robots / vehicles is also rendered possible.

[0019] These and other characteristics of the invention will be clear from the following description of a preferential form of embodiment, given as a non-restrictive example, with reference to the attached drawings wherein:

Fig. 1 is a perspective view of a prior art storage system;

Fig. 2 is a sectional view of a prior art robot or vehicle forming part of a storage system as illustrated in fig. 1;

Fig. 3 is a perspective base view of a remotely operated vehicle according to the present invention;

Fig. 4 is a perspective top view of a remotely operated vehicle according to the present invention;

Fig. 5 is a perspective top view of a robot assembly comprising a remotely operated vehicle according to the present invention, a storage bin and a fully enclosing cover,

Fig. 6 is a perspective top view of a bin storing grid and a vehicle support in accordance with the present invention;

Fig. 7 is a perspective side view of a bin storing grid and a vehicle support in accordance with the present invention;

Fig. 8 is a perspective side view of part of a storage system in accordance with the present invention including a bin storing grid, a vehicle support and a remotely operated vehicle; and

Fig. 9 is a schematic top view of a remotely operated vehicle moving on a two dimensional matrix of supporting rails.

Fig. 1 is a schematic, partly cut perspective view of a storage system according to the prior art, and fig. 2 is a sectional view of a corresponding prior art robot. Both figures have already been referred to earlier in the text.

Fig. 3 and 4 gives a perspective view in two different angles of the inventive robot 1 comprising a rectangular vehicle body or framework 4 with a cavity 7 centrally arranged within the body 4, a top lid 72 covering the top part of the body 4, a first set of four wheels 10 mounted inside the cavity 7 and in parallel to the interior walls of the body 4 and a second set of four wheels 11 mounted in parallel to the exterior walls of the body 4. The first and second set of wheels 10,11 are oriented perpendicular to each other. Further, the vehicle body 4 also includes side parts 5,5a,5b arranged on both sides of the cavity 7 along at least one of the robots 1 direction of movements. For the sake of clarity a Cartesian coordinate system is shown with its X, Y and Z axes aligned along the principal directions of the rectangular vehicle body 4. The size of the cavity 7 is adapted to contain necessary component for a lifting device 9 and to at least completely contain the largest storage bin 2 intended to be picked up by the robot 1.

Fig. 5 gives a perspective view of a robot assembly where the body 4 is completely covered by an enclosing cover 73 comprising handles 74 and transmission means / control panel 75. The design of the enclosing cover 73 is adapted to the particular shape given by the body 4 and the protruding wheels 10. Fig. 5 also shows a small part of a storage bin 2 arranged fully inside the cavity 7 and a small part of the lifting device 9. The latter is preferably composed of inter alia four vertically moveable metal bands suspended on the cavity facing side of the top lid 72 in their upper ends and steering rods at the lower ends capable of being steered and fastened into adapted cavities / areas in the storage bin 2 to be picked.

[0020] The structural principles of a grid assembly comprising a bin storing structure or grid 15, integrated supporting rails 13 constituting the vehicle support 14 and a grid supporting

base 76 are illustrated in figs. 6 and 7. The grid 15 comprises a plurality of pillars being arranged with internal distances adapted to accommodate storage bins 2 to be stored in stacks inside the grid 15. The rectangular arrangements of four adjacent pillars therefore constitute a storage column 8. Both the pillars and the rails 13 may be made of Aluminium. As for fig. 3 and 4 a Cartesian coordinate system is shown aligned along the principal directions of the grid assembly to ease the understanding. The supporting rails 13 form a two dimensional matrix of rectangular meshes, and the cross sectional area of most of these meshes coincide with the cross sectional area of each storage columns 8 set up by the underlying grid 15. The meshes at the border area 17,18 of the vehicle support 14 (at both sides in direction Y) is illustrated with cross sectional areas smaller than the remaining meshes. The size of the border meshes 17,18 should preferably be adapted to the degree of extension beyond a central storage column 8a situated immediately below the cavity 7 of the robot 1 when the latter is in a position for initiating pick up of a storage bin 2 contained in the central storage column 8a (see fig. 8 and 9). In this way the robot 1 may reach all the storage columns 8 in the storage system 3, i.e. independently of the robot orientation in the Y direction. For example, if the robot 1 extends exactly over the cross sectional area of one central storage column 8a in the X direction and over $\frac{1}{2}$ of the cross sectional area of the adjacent storage column 8b in the Y direction, the cross sectional area of the meshes 17,18 at the border area in the Y direction should be approximately $\frac{1}{2}$ of the cross sectional area of the remaining meshes. The primary function of these border meshes 17,18 is thus to allow sufficient space for the robot 1 having the novel design.

[0021] Fig. 8 shows the robot 1 in a lifting position above the central storage column 8a adjacent to the border area 17,18 of the grid assembly. The vehicle lifting device 9 is in this embodiment lowered a distance into the central storage column 8a in order to hook onto and lift up the underlying storage bin 2. As seen in the exemplary situation in figs. 8 the robot 1, having the body 4 extended in the Y direction compared to the X direction, may be driven all the way to the edge of the grid 15 when the border area is designed with additional border meshes 17,18 with a Y directional width approximately $\frac{1}{2}$ of the Y directional widths of the remaining meshes in the grid 15.

[0022] To better illustrate the movement of the robot 1 on the supporting rails 13 constituting the vehicle support 14 some exemplary positions of robots 1 on a grid assembly is illustrated in fig. 9. The thick arrows drawn in the centre of the robots 1 indicate allowed moving directions. When the robot 1 is situated with its cavity 7 exactly above a central storage column 8a, as is the case for the top left and mid centred robot 1, the arrangement of the supporting rails 13 allow movement in both X and Y directions. Any other positions on the grid assembly restrict the robot's 1 movement on the vehicle support 14 either in X direction (lower right robot 1) or in Y direction (top centered and bottom left robot 1). To allow determination of the robot position it is considered advantageous to equip each robot 1 with one or more position sensors 16, for example optical sensors. Such sensors should 16 preferably be mounted in one or more areas of the robot 1 which ensures that the sensors 16 have both non-obstructed view to the underlying supporting rails 13 and that they pass directly above or close to the positions on the vehicle support 14 in which the rails 13 are crossing. The readings from the sensors 16 may

inter alia dictate the further movement of the robot 1 and/or the operation of the vehicle lifting device 9.

[0023] All operations of the robot 1 are controlled by wireless communication means 75 and remote control units. This includes control of the robot movement, the vehicle lifting device and the position measurements.

[0024] In the preceding description, various aspects of the apparatus according to the invention have been described with reference to the illustrative embodiment. For purposes of explanation, specific numbers, systems and configurations were set forth in order to provide a thorough understanding of the apparatus and its workings. However, this description is not intended to be construed in a limiting sense. Various modifications and variations of the illustrative embodiment, as well as other embodiments of the apparatus, which are apparent to persons skilled in the art to which the disclosed subject matter pertains, are deemed to lie within the scope of the present invention.

List of reference numerals / letters:

[0025]

- 1
Remotely operated vehicle / robot
- 2
Storage bin
- 3
Storage system
- 4
Vehicle body / framework
- 5
First section (of vehicle body) / component section / side parts
- 5a
First section, left
- 5b
First section, right
- 6
Vehicle driving means / motor unit
- 7
Vehicle storage space / second part / cavity / centrally arranged cavity
- 8
Storage column
- 8a
Central storage column
- 8b

9	Adjacent storage column
10	Vehicle lifting device
11	First set of vehicle rolling means / First set of wheels
12	Second set of vehicle rolling means / Second set of wheels
13	Bin receiving opening
14	Supporting rail
15	Vehicle support
16	Bin storing structure / grid
17	Position sensing means / position sensor
18	Left outer lateral border area of vehicle support / left border mesh
50	Right outer lateral border area of vehicle support / right border mesh
60	Bin lift device
70	Delivery station / port
72	Yoke / overhang
73	Top lid
74	Enclosing cover
75	Handles
76	Transmission means / control panel / wireless communication means
	Grid supporting base

REFERENCES CITED IN THE DESCRIPTION

This list of references cited by the applicant is for the reader's convenience only. It does not

form part of the European patent document. Even though great care has been taken in compiling the references, errors or omissions cannot be excluded and the EPO disclaims all liability in this regard.

Patent documents cited in the description

- WO9849075A [0003]
- NO317366 [0003]

PATENTKRAV

1. Beholderopbevaringssystem (3), der omfatter en tredimensional beholderopbevaringsstruktur (15) og en flerhed af robotkøretøjer (1), der kan bevæges oven på beholderopbevaringsstrukturen (15) for at hente opbevaringsbeholdere (2) fra
5 beholderopbevaringsstrukturen (15), hvilken beholderopbevaringsstruktur (15) omfatter:
- en flerhed af piller, der er placeret med interne afstande og i et rektangulært arrangement, der er tilpasset til at modtage opbevaringsbeholderne (2), hvor det rektangulære arrangement af pillerne definerer opbevaringssøjler (8, 8a, 8b) til opbevaringsbeholderne (2),
 - bæreskiner (13) og
 - 10 - en opbevaringsbeholderleveringsstation (60),
hvilken flerhed af robotkøretøjer (1) hver omfatter et køretøjslegeme (4), der omfatter:
 - et første sæt rullemidler (10) til bevægelse af robotkøretøjet (1) langs bæreskinne (13) i den første retning (X),
 - et hulrum (7) til modtagelse af en opbevaringsbeholder (2), og
 - 15 - en hæveanordning (9) til hentning af en opbevaringsbeholder (2) fra en opbevaringssøjle (8, 8a, 8b) og opbevaring af opbevaringsbeholderen (2) i hulrummet (7),
hvor hulrummet (7) er anbragt centralt inde i køretøjslegemet (4),
kendetegnet ved, at
 - bæreskinne (13) er anbragt i en todimensional matrix oven på pillerne og
 - 20 tilvejebringer en køretøjsbærer (14) til flerheden af robotkøretøjer (1), der gør det muligt for hvert robotkøretøj (1) at bevæge sig på tværs af beholderopbevaringsstrukturen (15) i en første retning (X) og i en anden retning (Y), der er vinkelret på den første retning (X), ved, at
 - beholderopbevaringsstrukturen (15) omfatter en beholderhæveanordning (50),
der er indrettet til at hente opbevaringsbeholdere (2) fra flerheden af robotkøretøjer (1) og
 - 25 transportere opbevaringsbeholderne (2) i en vertikal retning fra et øvre niveau af beholderopbevaringsstrukturen (15) til leveringsstationen (60), og ved, at
 - køretøjslegemet (4) omfatter et andet sæt af rullemidler (11) til bevægelse af robotkøretøjet (1) langs bæreskinne (13) i den anden retning (Y).
- 30 2. Beholderopbevaringssystem (3) ifølge krav 1, kendetegnet ved, at køretøjslegemet (4) omgiver mindst en del af hulrummet (7).
3. Beholderopbevaringssystem (3) ifølge krav 2, kendetegnet ved, at køretøjslegemet (4) omfatter sidedele (5, 5a, 5b) anbragt på begge sider af hulrummet (7) langs mindst én af

robotkøretøjets (1) bevægelsesretninger (X, Y).

4. Beholderopbevaringssystem (3) ifølge et hvilket som helst af de foregående krav, kendetegnet ved, at robotkøretøjet (1) omfatter et øvre låg (72), der dækker den øvre del af køretøjslegemet (4).

5. Beholderopbevaringssystem (3) ifølge et hvilket som helst af de foregående krav, kendetegnet ved, at hulrummet (7) har en nedadvendende åbning til opbevaringsbeholderen (2).

6. Beholderopbevaringssystem (3) ifølge et hvilket som helst af de foregående krav, kendetegnet ved, at begge sæt af køretøjsrullemidler (10, 11) er anbragt symmetrisk omkring hulrummet (7) i nærheden af de nedre hjørner af robotkøretøjet (1).

7. Beholderopbevaringssystem (3) ifølge et hvilket som helst af de foregående krav, kendetegnet ved, at det første og det andet sæt af rullemidler (10, 11) hvert omfatter mindst fire hjul.

8. Fremgangsmåde til drift af et beholderopbevaringssystem (3), der omfatter en tredimensional beholderopbevaringsstruktur (15) og en flerhed af robotkøretøjer (1), der kan bevæges oven på beholderopbevaringsstrukturen (15) for at hente opbevaringsbeholdere (2) fra beholderopbevaringsstrukturen (15), hvilken beholderopbevaringsstruktur (15) omfatter:

- en flerhed af piller, der er placeret med interne afstande og i et rektangulært, der er tilpasset til at modtage opbevaringsbeholdere (2), hvor det rektangulære arrangement af pillerne definerer opbevaringssøjler (8, 8a, 8b) til opbevaringsbeholdere (2),

- bæreskinner (13), der er anbragt i en todimensional matrix oven på pillerne og tilvejebringer en køretøjsbærer (14) til flerheden af robotkøretøjer (1), der gør det muligt for hvert robotkøretøj (1) at bevæge sig på tværs af beholderopbevaringsstrukturen (15) i en første retning (X) og en anden retning (Y), der er vinkelret på den første retning (X),

- en opbevaringsbeholder-leveringsstation (60), og
- en beholderhæveanordning (50), der er indrettet til at transportere opbevaringsbeholdere (2), i en vertikal retning, fra et øvre niveau af beholderopbevaringsstrukturen (15) til leveringsstationen (60),

og hvilken flerhed af robotkøretøjer (1) hver omfatter et køretøjslegeme (4), der

omfatter:

- et første sæt rullemidler (10) til bevægelse af robotkøretøjet (1) langs bæreskinnerne (13) i den første retning (X),

- et andet sæt rullemidler (11) til bevægelse af robotkøretøjet (1) langs bæreskinnerne (13) i den anden retning (Y),

- et hulrum (7) til modtagelse af en opbevaringsbeholder (2), hvilket hulrum (7) er anbragt centralt inde i køretøjslegemet (4),

- en hæveanordning (9) til hentning af en opbevaringsbeholder (2) fra en opbevaringssøjle (8, 8a, 8b) og opbevaring af opbevaringsbeholderen (2) i det centrale hulrum (7),

hvilken fremgangsmåde omfatter trinnene med:

- placering af ét af flerheden af robotkøretøjer (1) over én af opbevaringssøjlerne (8a, 8b), således at det centrale hulrum (7) af køretøjslegemet (4) flugter med opbevaringssøjlen (8a, 8b),

- anvendelse af køretøjslegemets (4) hæveanordning (9), hentning af en opbevaringsbeholder (2) fra opbevaringssøjlen (8a, 8b) og opbevaring af opbevaringsbeholderen (2) inde i det centrale hulrum (7),

- anvendelse af det første og det andet sæt af rullemidler (10, 11), bevægelse af robotkøretøjet (1) langs bæreskinnerne (13) til beholderhæveanordningen (50) og overføring af opbevaringsbeholderen (2) til beholderhæveanordningen (50), og

- anvendelse af beholderhæveanordningen (50), transport af opbevaringsbeholderen (2) ned i en vertikal retning fra det øvre niveau af beholderopbevaringsstrukturen (15) til leveringsstationen (60).

9. Fremgangsmåde ifølge krav 8, hvor køretøjslegemet (4) omgiver mindst en del af det centrale hulrum (7).

10. Fremgangsmåde ifølge krav 9, hvor køretøjslegemet (4) omfatter sidedele (5, 5a, 5b) anbragt på begge sider af hulrummet (7) langs mindst én af robotkøretøjets (1) bevægelsesretninger (X, Y).

11. Fremgangsmåde ifølge et hvilket som helst af kravene 8-10, hvor robotkøretøjet (1) omfatter et øvre låg (72), der dækker den øvre del af køretøjslegemet (4).

12. Fremgangsmåde ifølge et hvilket som helst af kravene 8-11, hvor det centrale hulrum (7) har en nedadvendende åbning til opbevaringsbeholderen (2).

13. Fremgangsmåde ifølge et hvilket som helst af kravene 8-12, hvor begge sæt af køretøjsrullemidler (10, 11) er anbragt symmetrisk omkring hulrummet (7) i nærheden af de nedre hjørner af robotkøretøjet (1).

14. Fremgangsmåde ifølge et hvilket som helst af kravene 8-13, hvor det første og det andet sæt af rullemidler (10, 11) hvert omfatter mindst fire hjul.

DRAWINGS

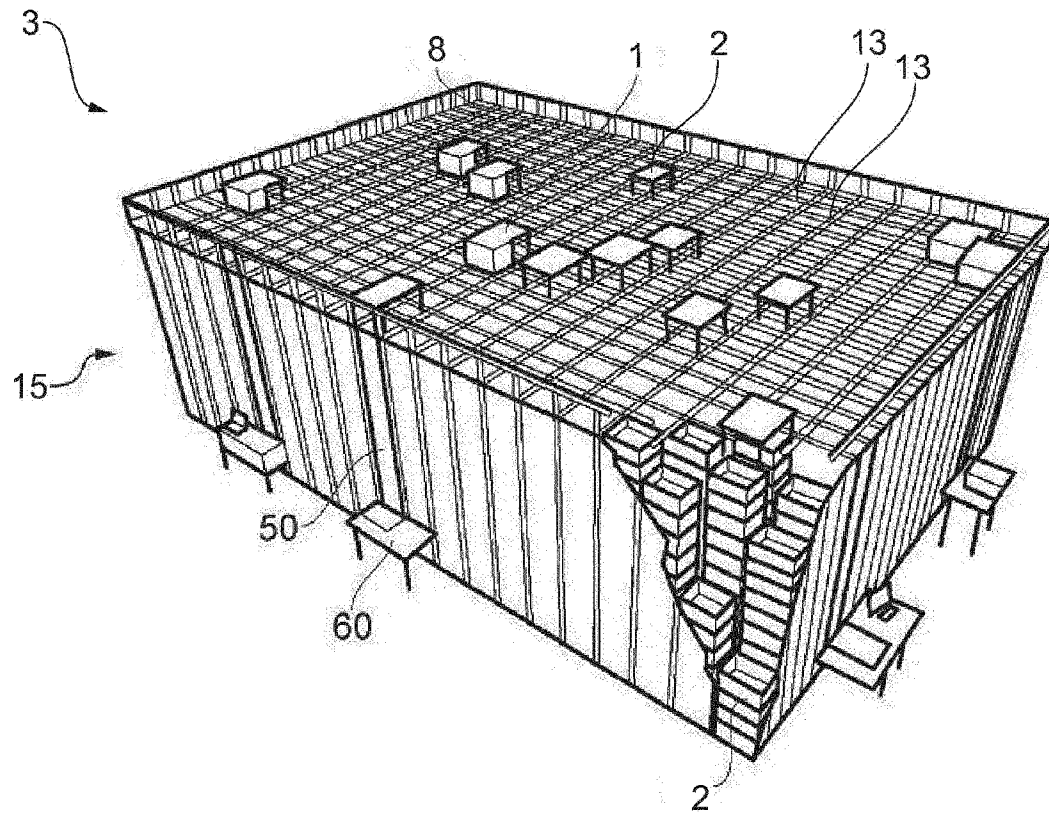


FIG. 1(Prior Art)

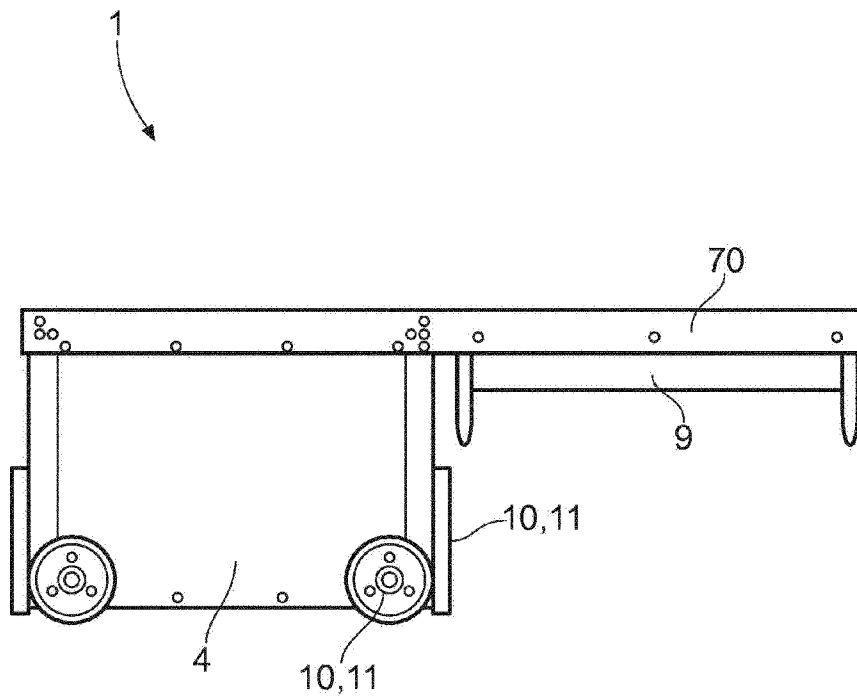


FIG. 2 (Prior Art)

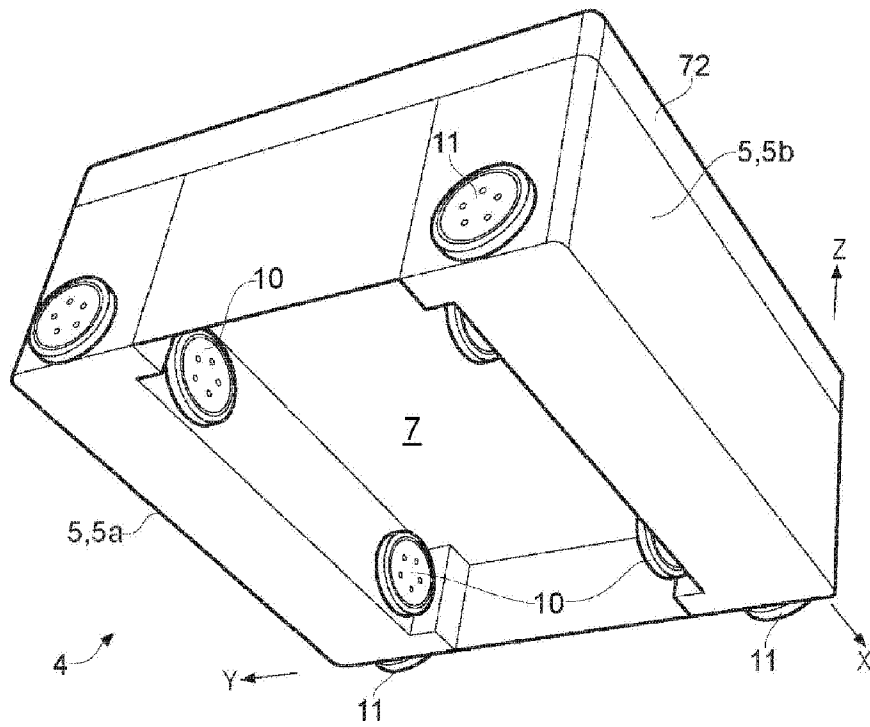


FIG. 3

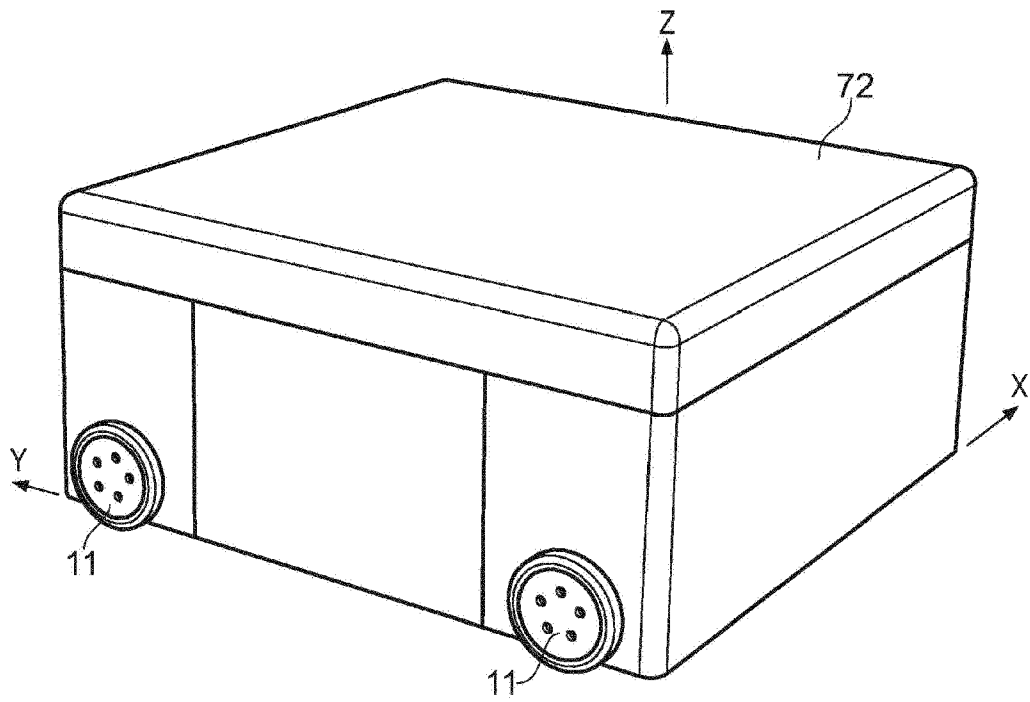


FIG. 4

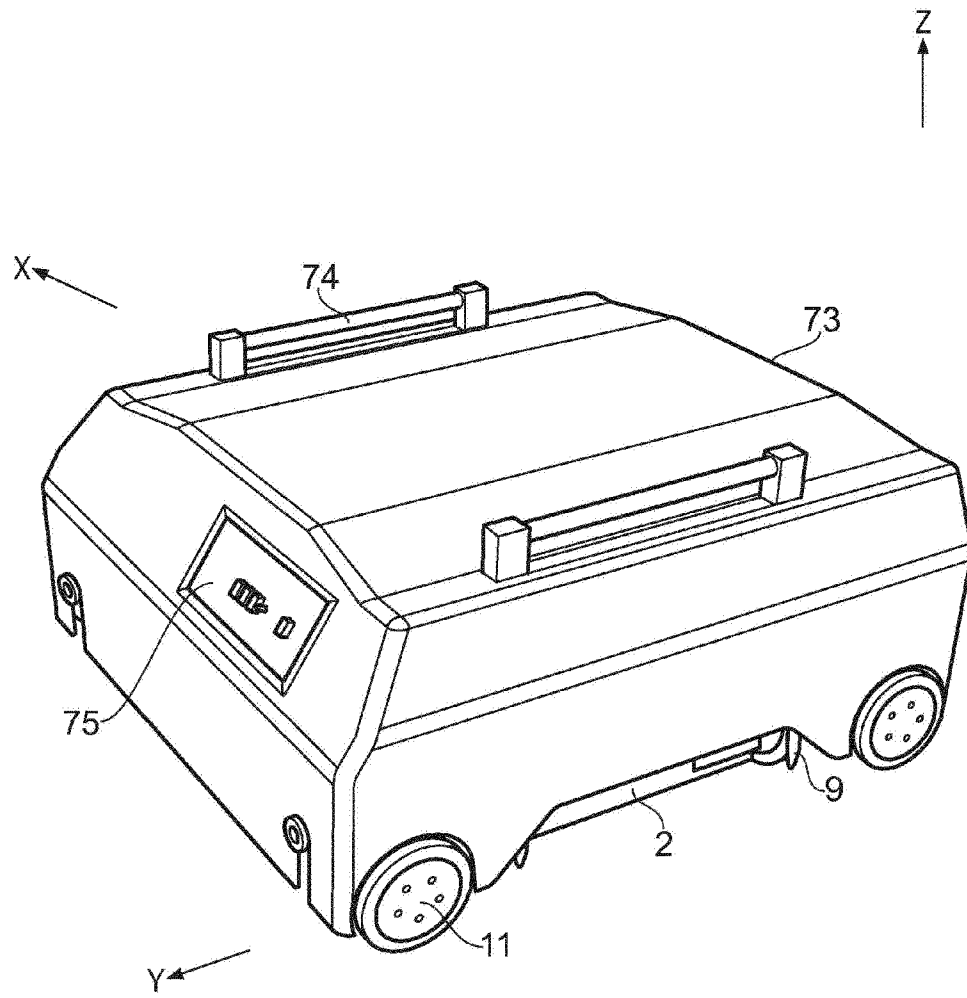


FIG. 5

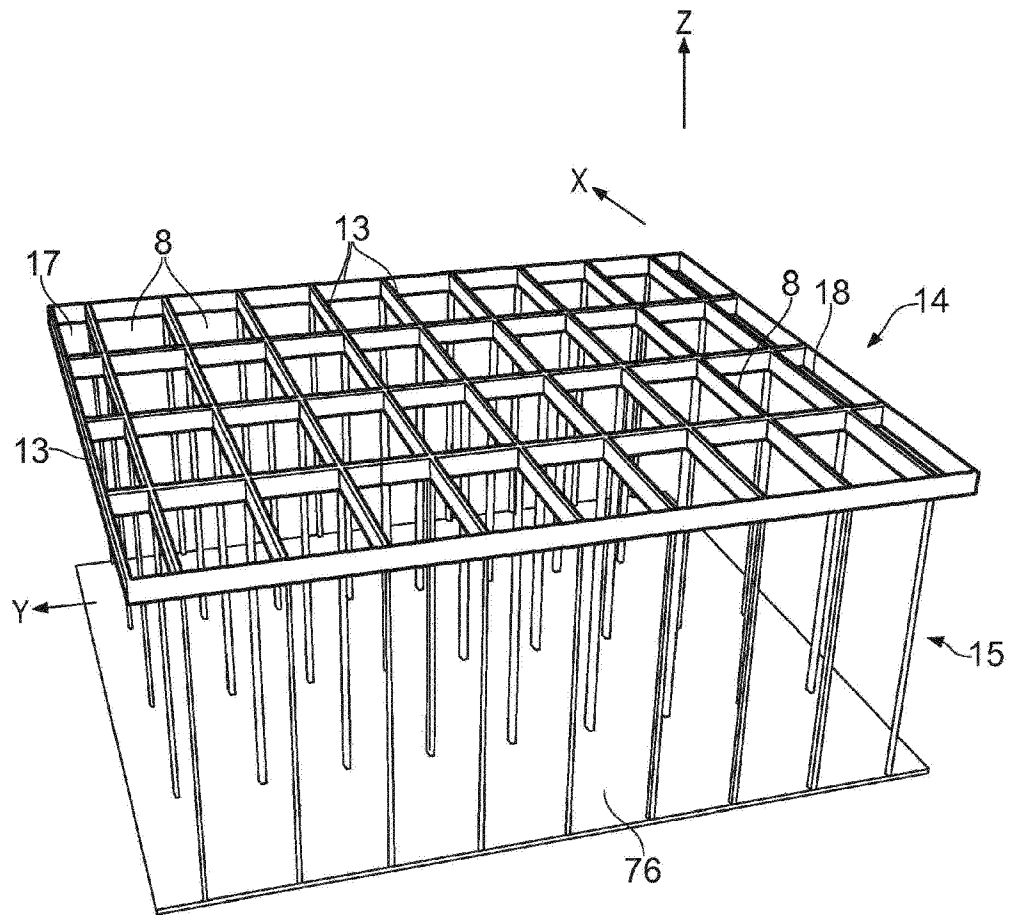


FIG. 6

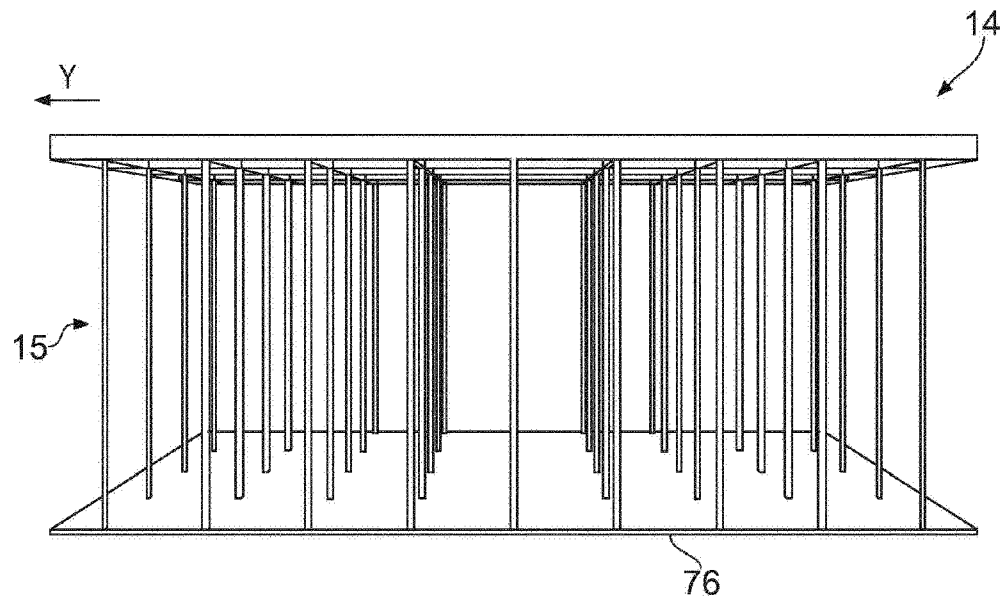


FIG. 7

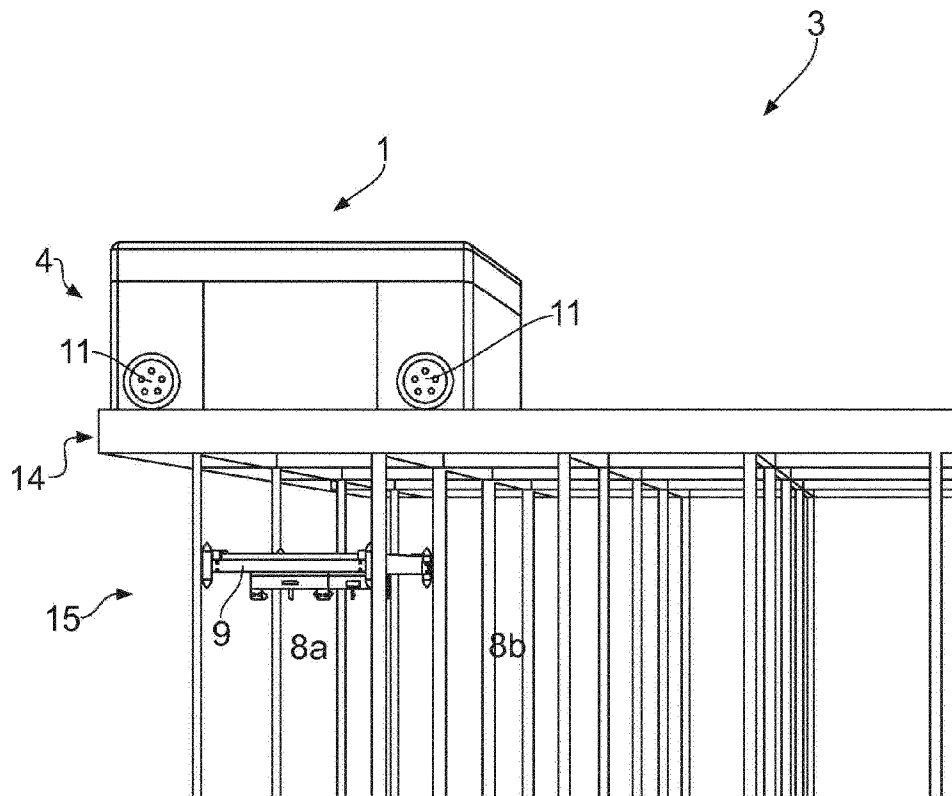


FIG. 8

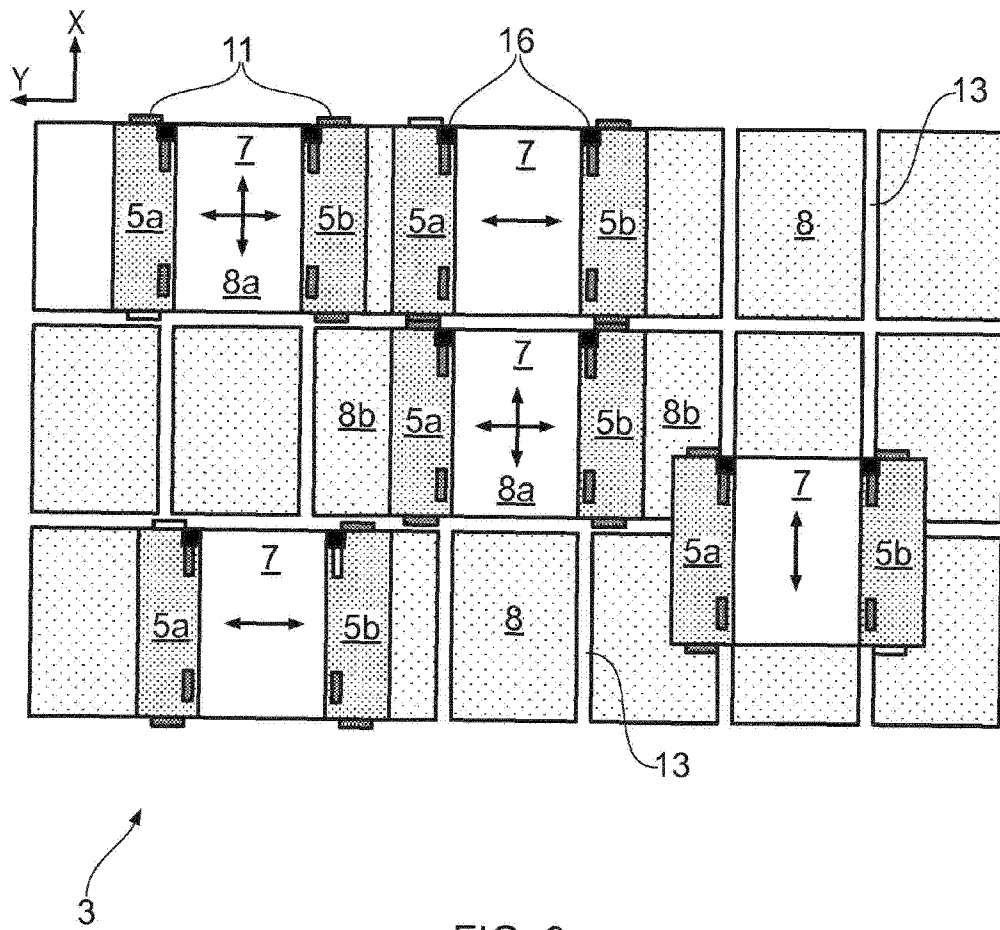


FIG. 9