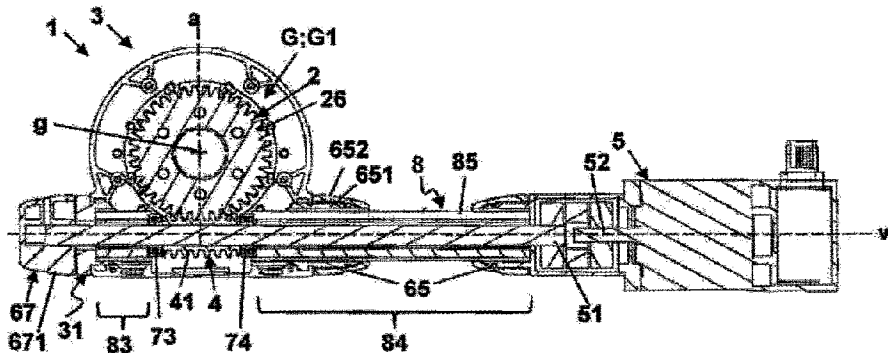




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(54) Titre : MANIPULATEUR POURVU D'ARTICULATIONS ET PROFILE MULTIFONCTIONNEL POUR CELUI-CI  
 (54) Title: MANIPULATOR HAVING JOINTS AND MULTI-FUNCTIONAL PROFILE FOR SAME



(57) **Abrégé/Abstract:**

The invention relates to a manipulator comprising at least one profile as a supporting connection element between two joints (1) and/or between a motor (5) and joint (1). In order to provide a manipulator that is simply constructed and offers a multitude of design possibilities, according to the invention, the profile is designed as a multi-functional profile with an internal channel (81) and at least one lateral receiving groove, and at least one further multi-functional profile which is designed as a shaft and with at least sections thereof being structurally identical to the multi-functional profile at least in terms of the profile formation, or designed as a rack and with at least sections thereof being structurally identical to the multi-functional profile at least in terms of the cross-sectional contour.

## ABSTRACT

The invention relates to a manipulator comprising at least one profile as a supporting connection element between two joints (1) and/or between a motor (5) and joint (1). In order to provide a manipulator that is simply constructed and offers a multitude of design possibilities, according to the invention, the profile is designed as a multi-functional profile with an internal channel (81) and at least one lateral receiving groove, and at least one further multi-functional profile is provided which is designed as a shaft and with at least sections thereof being structurally identical to the multi-functional profile at least in terms of the profile formation, or designed as a rack and with at least sections thereof being structurally identical to the multi-functional profile at least in terms of the cross-sectional contour.

## **MANIPULATOR HAVING JOINTS AND MULTI-FUNCTIONAL PROFILE FOR SAME**

### **Technical Field**

5           The invention concerns a manipulator comprising at least one profile member as a supporting connecting element between two joints of the manipulator and/or between a joint and a motor associated therewith.

### **Background**

10           A manipulator of the general kind set forth is known from DE 20 2014 101 342 U1, wherein the connecting element is in the form of a hollow profile portion which however scarcely permits possible variations in regard to differing configurations of the manipulator.

### **Summary**

15           An object of the invention is to provide a manipulator of the general kind set forth, which is of a simple structure and which affords a multitude of design options.

          According to the invention the object is attained by the features of a  
20   manipulator comprising at least one profile member as a supporting connecting element between two joints of the manipulator and/or between a motor and a joint, wherein the at least one profile member is in the form of a multi-function profile member having an internal passage and at least one lateral receiving groove, wherein there is provided at least one further multi-  
25   function profile member which is in the form of a shaft, and the two multi-function profile members are at least portion-wise of identical structure at least in respect of their profile configuration.

          The specified object is already attained in that the profile member is in the form of a multi-function profile member having an internal passage and

at least one lateral receiving groove, that there is provided at least one further multi-function profile member which is in the form of a shaft and that the two multi-function profile members are at least portion-wise of identical structure at least in respect of their profile configuration.

5           By virtue of the use of the multi-function profile member it is possible on the one hand, as described in greater detail hereinafter, to easily develop different configurations of the manipulator which can be inexpensively adapted to given respective tasks. On the other hand, simplifying construction and assembly, the two claimed multi-function profile members  
10 are of identical structure at least in respect of their profile configuration. That structural identity in respect of the profile configuration is not related to the absolute sizes of the two multi-function profile members but solely to the cross-sectional shape or cross-sectional contour. Structural identity means that the two multi-function profile members are at least similar and  
15 preferably identical in respect of their cross-sections. They can however also be congruent, that is to say equivalent. In addition the multi-function profile member is also provided between motor and joint whereby thermal influence on the joint is at least minimised. Furthermore the motor can form a counterweight to the joint. Furthermore the motor can be of any kind and  
20 can only satisfy the requirement that it is suitable for the respective use. Advantageous inter alia because of the low number of lines required the motor used can be a brushless dc motor.

In an alternative way of attaining the object it is proposed that the profile member is in the form of a multi-function profile member having an  
25 internal passage and lateral receiving grooves, that there is provided at least one further multi-function profile member which is in the form of a toothed rack and that the two multi-function profile members are of identical structure at least in respect of their cross-sectional configuration. The variability already referred to above is expanded with the tooth profile.

In a further configuration of the manipulator the further multi-function profile member can also be in the form of a supporting connecting element between two joints of the manipulator, between a joint and a working head or between a joint and a motor. It can thus also contribute to the stability and operational stiffness of the manipulator. The multi-function profile member can generally be in the form of a supporting connecting element between two joints of the manipulator, between a joint and a working head or between a joint and a motor.

In an advantageously simple fashion, the multi-function profile members can each have an outside contour which is circular at least in its basic shape. That outside profile of the multi-function profile member, that is circular at least in its basic shape, makes it possible to rotatably mount the multi-function profile member in a simple fashion in order for example to use it for torque transmission. In addition, if required, a gear element like a spur gear can be mounted by way of the at least one outside profile which is circular in its basic shape, in a simple fashion like by means of a clamping fit, for example as a further transmission element. The multiple use options of the multi-function profile member will also be apparent from the fact that, besides its use as a supporting and stiffening connecting element, it can also be in the form of a toothed rack.

Advantageously the lateral receiving grooves can be opened outwardly transversely to the longitudinal direction of the respective multi-function profile member. In that way they are accessible from the exterior, which facilitates in particular assembly and dismantling.

In a further configuration of the manipulator the lateral receiving grooves are arranged peripherally in equally spaced relationship. That spacing can be peripherally at least substantially identical. Peripherally adjacent outside grooves can be arranged on the multi-function profile member, starting from the peripheral centre thereof as a reference point,

peripherally at least substantially at equal spacings. The outer grooves can be of a different configuration according to their intended purpose of use.

By way of example a receiving groove forming the first receiving groove can be provided for fixing the multi-function profile member to the housing and/or for fixing additional components, a receiving groove in the  
 5 form of a second receiving groove can be provided for positioning the further transmission element relative to the housing and/or relative to the gear wheel and/or a receiving groove forming the third receiving groove can be provided for a measuring element.

10 For example, for fixing the multi-function profile member to the housing or for fixing further devices to the multi-function profile member the second receiving groove and/or the third receiving groove can be of an undercut configuration. In particular, there can be provided two first receiving grooves whose cross-sectional profiles are preferably mutually  
 15 congruent. In particular, the first receiving groove can be arranged diametrically with respect to the second receiving groove with respect to a longitudinal direction of the multi-function profile member.

The receiving grooves can be peripherally equally spaced from each other. If there are two first receiving grooves, that is to say a total of four  
 20 receiving grooves, then the receiving grooves can be arranged in crossed relationship with each other with respect to the longitudinal axis. In particular, in each case with respect to the longitudinal axis, the third receiving groove can be arranged diametrically with respect to the fourth receiving groove.

25 In an advantageous development of the manipulator the internal passage of the multi-function profile member can be of a substantially circular cross-section. That permits engagement therethrough, in favourable force-mechanical relationship, of a shaft of round cross-section, with the shaft being protected in the passage. In addition the diameter of the shaft

can be less than the diameter of the internal passage so that the shaft, arranged at a given spacing, preferably of the order of magnitude of a slip, can rotate freely in the passage.

5 The internal passage can further have at least one lateral longitudinal chamber for receiving lubricant, for passing a line therethrough and/or for saving on material.

10 In a further specification of the manipulator a respective multi-function profile member can be operationally connected to a joint at the driven side and the drive side of the joint. This means that those two multi-function profile members can perform different functions in respect of a joint.

15 In a development of the manipulator the joints can each have a motor drive with a motor and a transmission. The transmission can have a gear wheel rotatable about a transmission axis of rotation and a further transmission element. The gear wheel can be operatively connected to a further transmission element by for example the further transmission element engaging the periphery of the gear wheel. For the further transmission element the transmission can have a operative axis which is spaced with respect to the transmission axis of rotation and by way of which the further transmission element is arranged mounted in or to the housing.

20 A multi-function profile member can be arranged in the transmission axis of rotation. In addition, a multi-function profile member can be arranged in the operative axis of the respectively associated joint. In particular, the multi-function profile member can engage the gear wheel at its end. Alternatively, or additionally a multi-function profile member can be arranged relative to the operative axis tangentially or at the end in relation to the further transmission member.

25 In particular, the transmission can be in the form of a worm transmission. For that purpose, the further transmission element can be in the form of a worm and the operative axis can be in the form of a drive shaft

for the worm. The drive shaft can form an axial prolongation of the motor shaft, that is coupled to the drive end. The worm can be arranged non-rotatably on the operative axis. In addition, the operative axis can be rotatably mounted axially preferably at both sides of the worm at or in the receiving portion. The drive shaft can be arranged to be guided in a multi-function profile member. In the case of the worm drive the hollow profile member can be arranged non-rotatably and non-displaceably relative to the housing at and/or in same. For that purpose, suitable projections from the housing can engage into the first receiving groove or the first receiving grooves, in which case the profile thereof is advantageously adapted to the undercut configuration of the respectively associated receiving groove. To produce improved axial non-displaceability of the worm on the drive shaft the multi-function profile member can be divided in the region of the worm into two portions, wherein the portions are respectively arranged with an end towards the worm, in particular by way of a mounting means provided for the drive shaft, at the ends, guided in relation to the worm. The two portions can be arranged spaced from each other over the axial extent of the worm and the drive shaft prolongation.

In a development of the manipulator the transmission can be in the form of an inverted worm transmission with a gear wheel at the drive side and a further transmission element at the driven side. In particular, it can be provided that the multi-function profile member forms the operative axis. The worm gear can be arranged non-rotatably on the hollow profile member. The hollow profile member in turn can be mounted rotatably at or in the receiving portion. That affords the possibility that, in addition to the multi-function profile member in the form of the drive shaft, it is possible to provide a further drive shaft which extends in the passage as the drive shaft for the further transmission element. Without transmitting a torque to the hollow profile member, the drive shaft can be guided through the hollow

profile member past or through the joint in order for example to couple a torque into an adjacent joint. The gear wheel can have a peripheral male thread and the further transmission component can have a spur tooth arrangement adapted to the male thread. The multi-function profile member  
5 can be arranged as a prolongation of the motor axis. It can be non-rotatably connected at its end by way of a coupling to the motor shaft.

In a further advantageous embodiment of the manipulator the transmission can be in the form of a linear transmission. In particular, the gear wheel can be in the form of a sprocket and the further transmission  
10 element can be in the form of a linear element, in particular a toothed rack element. The toothed rack element can at the same time form the operative axis and can be arranged linearly displaceably on the receiving portion. In an advantageous development the linear element, in particular, the toothed  
15 rack element, can be fixed in the first receiving groove of the hollow profile member, that in the installation position is open towards the gear wheel. Preferably the linear element is arranged invariably in position in the receiving groove. Preferably the second receiving groove is arranged at an  
outside of the hollow profile member, that is in diametrically opposite relationship to the operative axis.

20 With a further increase in the number of possible variations it can be provided that the joint overall and/or the transmission components are respectively of a modular structure. In addition, the manipulator can be of a modular structure. Accordingly, the manipulator, in particular in its  
components like joint, transmission, multi-function profile member and  
25 motor, by virtue of the modular structure, can be easily assembled in accordance with a modular structural principle with a wide range of variations.

The subject-matter of the claimed invention is also a multi-function profile member suitable for a manipulator, as such, which in the simplest

configuration has at least one internal passage, an outside contour which is circular in its basic shape, and lateral receiving grooves which are opened outwardly transversely to the longitudinal direction of the multi-function profile member.

5 In advantageous embodiments the multi-function profile member has one or more of the features set forth as preferred features hereinbefore (in any combination).

### **Brief Description of the Drawings**

10 Further details and advantages of the invention will be apparent hereinafter without restriction on the scope of protection from the description of a preferred embodiment with reference to the accompanying drawings in which:

15 Figures 1A-1C each show a view of an embodiment of a joint as part of a manipulator with joints,

Figure 2 shows a longitudinal sectional view of a further embodiment of the manipulator with another joint,

Figures 3A-3B each show a side view of cooperating transmission portions for the joint of Figure 2,

20 Figures 4A-4B each show a longitudinal sectional view of a further embodiment of the manipulator with another joint,

Figures 5A-5B each show a view of a multi-function profile member for the manipulator,

25 Figure 6 shows a perspective view of the multi-function profile member with the additional arrangement of a measuring element,

Figure 7 shows a perspective view of a toothed profile portion for arrangement at the multi-function profile member,

Figure 8 shows a perspective view of a sensor arrangement for arrangement at the multi-function profile member,

Figure 9 shows a longitudinal sectional view of a further embodiment of the manipulator with three joints coupled together,

Figures 10A-10B each show a view of a further embodiment of the manipulator with three joints coupled together,

5 Figure 11 shows a side view of a further embodiment of the manipulator with six joints coupled together, and

Figures 12A-12B each show a view of a further embodiment of the manipulator with respectively five and six joints coupled together.

10

### **Detailed Description**

Figures 1 to 12 shows various views, sectional views and individual views of respective embodiments of a manipulator M with joints 1. As can be seen in particular from Figures 1C and 9 the joints 1 each have a gear wheel 2 rotatable about a transmission axis of rotation g. As can be seen in particular from Figure 9 the gear wheel 2 is rotatably mounted at both sides by way of adaptors 22 in bearings 7 in a housing 3 of the joint 1. The two adaptors 22 each have at their side 23 remote from the end face 21 of the gear wheel 2, an opening 24 which is central with respect to the transmission axis of rotation g and has a female thread 25. The housing 3 has a receiving portion 31 for receiving a further transmission element 4.

20 The further transmission element 4 is arranged transversely, here perpendicularly, to the transmission axis of rotation g on an operative axis w. The operative axis w is positioned spaced in the spacing direction a relative to the transmission axis of rotation g. The transmission axis of rotation g, the spacing direction a and the operative axis w are arranged perpendicularly to each other. The transmission element 4 is operatively connected to the periphery of the gear wheel 2. The gear wheel 2 and the further transmission element 4 form a transmission G for transmission of a motor

torque which is coupled into the joint 1. The motor 5 is arranged spaced relative to the respectively associated joint 1.

Referring to Figures 1 and 10 the transmission G of the joint 1 is configured as a worm transmission G1 with a gear wheel 2 at the driven side, in the form of a worm gear 26, and a further transmission element 4 at the drive side, in the form of a worm 41. Here the operative axis w is a drive shaft 51 driven directly by a motor 5. The worm 41 is arranged in a clamping fit on the drive shaft 51. As can be seen from Figure 1C the drive shaft 51 is arranged protected and guided in a central internal passage 81 in a multi-function profile member 8. The internal passage 81 is of a substantially circular cross-section in respect of its basic shape. Opening laterally into the internal passage 81, here there are provided two longitudinal chambers 87 which are lateral in relation to the internal passage 81, for example for receiving lubricant, for passing a line therethrough and/or for saving on material. The longitudinal chambers 87 extend over the entire length of the multi-function profile member 8. In relation to their cross-section the longitudinal chambers 87 enlarge the internal passage 81. They are designed and arranged in mirror-image symmetrical relationship in relation to a connecting line between a second receiving groove 85 and a third receiving groove 86.

The multi-function profile member 8 is fixedly connected to the receiving portion. The multi-function profile member 8 is arranged as a supporting connecting element between joint 1 and motor 5. In this embodiment of the joint 1 the hollow profile member 8 serves as protection, guidance and reinforcement, in particular, as reinforcement in regard to use stiffness, of the portion of the manipulator M between the motor 5 and the joint 1. The drive shaft 51 is further mounted rotatably axially with respect to the operative axis w on both sides of the worm 41 by way of a respective bearing 7 at the receiving portion 31.

The hollow profile member 8 itself is arranged non-rotatably and non-displaceably relative to the receiving portion 31. For that purpose provided at both sides 23 of the hollow profile member 8 are first receiving grooves 82 or an undercut configuration, into which engage anchor projections on the receiving portion 31 for non-rotatably mounting the hollow profile member 8.

For engagement of the worm gear 26 into the worm 41 the hollow profile member 8 has two portions, that is to say a first portion 83 and a second portion 84. The two portions 83; 84 are arranged spaced from each other over the extent, axially with respect to the operative axis w, of the drive shaft 51 at the two bearings 7 supporting the hollow profile member 8 and the axial extent of the worm 41. The two portions 83; 84 respectively engage with an end towards the worm 41, at the ends thereof, at the bearing 7 associated therewith, that is to say in each case with respect to the direction from the setting unit towards the worm 41, a front bearing 73 and a rear bearing 74, wherein they are respectively supported at the receiving portion 31 with their other end that is remote from the worm 41.

The second portion 84, arranged at the right in Figure 1C, is supported by way of a clamping element 65. In the working position it bears peripherally in frictionally locking relationship radially outwardly against the second portion 84. The clamping element 65 is further arranged screwably on the receiving portion 31. The clamping element is so designed that, with progressive screwing at the receiving portion 31, it peripherally exerts a correspondingly increasing radial frictional force on the second portion 84, and in this application that causes frictional engagement with the second portion 84. The multi-function profile member 8 thus serves here as a carrier for the clamping elements 65 and for fixing same.

The first portion 83, arranged at the left in Figure 1C, bears with its supported end in force-transmitting relationship against a setting unit 67 for adjustment of a play, which is axial with respect to the operative axis, in the

operative connection between the worm gear 26 and the worm 41. The setting unit 67 has an adjusting device 671, by way of which, for adjusting play, the first portion 83 of the hollow profile member 8 is pressed against the front bearing 73 axially in the direction from the setting unit 67 towards  
 5 the worm 41, which in turn can be pressed against the worm 41 as far as freedom from play. In that way the multi-function profile member is at the same time in a further function used as part of the setting unit 67.

Figure 2 is a cross-sectional view in relation to the transmission axis of rotation g showing a joint 1 as part of the manipulator M. The transmission  
 10 G is here in the form of an inverted worm transmission G2. Conversely to the worm transmission G1 here the torque is coupled in at the drive side by way of the gear wheel 2 and coupled out at the driven side to the operative axis w by way of the further transmission element 4. As can be seen from Figures 3A-3B, corresponding to the reversal, the gear wheel 2 has a  
 15 peripheral male thread 27 and the further transmission portion 4 has a spur tooth arrangement 42. The multi-function profile member 8, which is thus at the driven side, forms the operative axis w. The spur gear 28 is fixedly arranged on the hollow profile member 8. For that purpose, provided at the spur gear 28 of the further transmission portion 4 are anchor elements 45,  
 20 by way of which they engage in frictionally locking relationship and/or positively locking relationship into the undercut first receiving grooves 82 of the multi-function profile member 8. Accordingly, here the multi-function profile member 8 serves as a carrier for the second transmission element 4. As the further transmission element 4 is mounted non-rotatably on the multi-  
 25 function profile member 8 the multi-function profile member 8, in an enlargement of its possible uses, becomes the shaft, insofar as it receives and transmits the torque of the further transmission element 4. The multi-function profile member 8 is here mounted rotatably to the housing 3 by way of two axially mutually spaced clamping elements 65. For rotatable

mounting thereof the multi-function profile member 8 has an outside profile which is circular in its basic shape. Figure 2 diagrammatically indicates the possibility of connecting the multi-function profile member 8 at its end in torque-transmitting relationship for example to two joints 1, more specifically to the further transmission element 4 of the joint 1 at the left in Figure 2 and/or to the gear wheel 2 of the joint 1 at the right in Figure 2.

In this embodiment of the joint the above-mentioned internal passage 81 is not required to constitute the inverted worm transmission G2. That affords the option of passing other components like lines or, as indicated by way of example in Figure 2, a further drive shaft 51, for example for a remote joint 1, through the hollow profile member 8 while being protected thereby, without the further drive shaft 51 transmitting a torque to the joint 1.

Figures 4A-4B respectively show a view of a further embodiment of the joint 1, insofar as here the transmission G is in the form of a linear transmission G3. To provide the linear transmission G3 the gear wheel 2 is in the form of a spur gear 28 and the further transmission element 4 is in the form of a toothed rack element 43. The toothed rack element 43 in the installation position is arranged fixed in a second receiving groove 85 of the multi-function profile member 8. Accordingly, the multi-function profile member 8 in a further possible use becomes the linear component of the linear transmission G3. In addition, the multi-function profile member 8 functions as the operative axis w.

The second receiving groove 85 is open towards the gear wheel 8 in the installation position for threaded engagement of the toothed rack element 43 and the spur gear 28. The toothed rack element 43 is mounted non-rotatably and non-displaceably on the hollow profile member. In the installation position it engages into the first receiving groove 82 by way of a foot 44 adapted to the undercut configuration. In addition, provided on both

sides of the toothed rack element 43 are clamping elements 65 which are arranged in a clamping fit on the hollow profile member 8 and against which the toothed rack element 43 bears axially against clamping elements 65. In that way the toothed rack element 43 is held axially non-displaceably in the receiving groove 84.

As can be seen from Figure 2 clamping elements 65 mounted by way of the multi-function profile member 8 respectively have two coaxial sleeves, that is to say a radially inner sleeve 651 and a radially outer sleeve 652 which are in threaded engagement by way of mutually facing conical screw threads. If, as in the case of the worm transmission G1, the multi-function profile member 8 is to be held fixedly relative to the housing 3, then for assembly purposes with progressive screwing the inner sleeve 651 is pressed by way of the outer sleeve 652 until frictionally locking engagement occurs against the multi-function profile member. If, as in the case of the inverted transmission G2, rotary bearing means are necessary or in the case of the linear transmission G3 linear displaceability of the multi-function profile member 8 is needed, then the two sleeves 651; 652 in themselves can be screwed until encountering an abutment condition, preferably with a self-locking action. As can be seen from Figure 2 that abutment can be implemented by a peripheral clamping ring 71 having radial projections 72, engaging radially inwardly into the multi-function profile member 8 in non-displaceable and non-rotatable relationship.

Figures 5A and 5B show a perspective view and a cross-sectional view of the multi-function profile member 8. The multi-function profile member 8, like also its above-described portions 83; 84, are respectively made in one piece. They can be cut to length from a preferably extruded profile bar to provide the respectively required length. The term multi-function profile member means just a bar of a given cross-sectional profile configuration.

The term multi-function profile member does not include possible components or devices arranged thereon.

Figures 5A and 5B clearly show the above-described arrangement and the configuration of the receiving grooves. Figure 7 shows just the toothed rack element 43 with its foot 44 adapted to the undercut configuration of the second receiving groove 85 associated therewith. As shown in Figure 6 arranged in the third receiving groove 86 for measuring a displacement travel of the toothed rack element 43 is a linear measuring element, here in the form of a magnetic strip Ma. A suitable sensor means R, a device for receiving and processing a travel measurement signal generated by the change in the magnetic field of the magnetic strip is shown in Figure 8. It is of a half-shell shape and is fixed to the receiving portion 31 centrally with respect to the operative axis w.

Figures 9-12 show different configurations of the manipulator M, wherein in this case up to six joints 1 are functionally operatively connected together to constitute the manipulator M. These are possible options by way of example for combining the joints 1 together. The manipulator M can be, in particular, a joint arm robot. Ideally the manipulator M is in the form of a 6-axis manipulator M.

In Figures 6-12 up to five joints 1 are arranged coaxially with respect to a common transmission axis G and in parallel spaced relationship. They are held in parallel spaced relationship with each other by way of a connecting device 9. As shown in Figure 9 a group with three joints 1 is arranged on a common transmission axis of rotation G, wherein the joint 1 at the left in Figure 9 has a worm transmission G1 and the other two joints 1 each have a linear transmission G3. A torque is coupled into the gear wheel 2 of the joint 1 adjacent thereto by the joint 1 having the worm transmission G1. A multi-function profile member 8 is arranged between the other two joints 1 with the linear transmission G3 for transmission of a torque between

the two joints 1. The multi-function profile member 8 is connected non-rotatably and non-displaceably to the gear wheels 2 of the two joints 1 at the ends by way of a respective connection mounting 53. Accordingly, in this case the multi-function profile member 8 serves as a torque-transmission shaft between the two joints 1 with the linear transmission G3.

Figures 10A to 10B each show a view of a further embodiment of the manipulator M with three joints 1 which are arranged in succession with respect to the operative axis w and which respectively have worm transmissions G1, the worm transmissions G1 of the joints 1 being of identical structure. The joints 1 are held spaced from each other by way of individual second portions 84 of a multi-function profile member 8. Similarly, to the embodiment of Figure 1 passed through those second portions 84 is a common drive shaft 51 which at the end ends in a first portion 84 of the multi-function profile member 8 and drives the worm transmissions G1 of all three joints 1.

In the embodiment of the manipulator M in Figure 11 the joints 1 can be divided from the point of view of their functional relationship into a first group U1 and a second group U2, wherein the second group U2 arranged at the top in Figure 11 has already been described with reference to Figure 9. The second group U2 is fixed to a base B. The two outer joints 1 of the first group U1 are respectively connected by way of a multi-function profile member 1 with incorporated toothed rack element 43 to a motor 5 which is arranged at the top in Figure 11 and the torque of which is transmitted to the respectively associated outer joint 1 by way of a drive shaft 51 (not visible here) which passes through the respective multi-function profile member 8. By virtue of the two joints 1 with linear transmission G3 the respectively associated multi-function profile member 8 with incorporated toothed rack element 43 is linearly displaced. As the gear wheels 2 of those two joints 1 are here non-rotatably connected together by way of a drive shaft portion 53

the two associated multi-function profile members 8 are displaced synchronously with each other. The joint 1 arranged centrally in the first group U1 is also equipped with a linear transmission G3 (not visible here), by which the multi-function profile member 8 passing through that joint 1 is  
 5 linearly displaced.

Figures 12A and 12B show a sectional view and a view from below with respect to the base B of a further embodiment of the manipulator M, here with five and six joints 1 respectively. In the underneath view shown in Figure 12B the toothed rack elements 43 fitted into the multi-function profile  
 10 members 8 are concealed as they face towards the gear wheel 2 of the respectively associated joint 1. The joints 1 can also be divided into two groups U2; U3. The joints 1 of both groups U2; U3 are arranged coaxially on a transmission axis of rotation g.

The group which here is at the left is the second group U2 which has  
 15 already been mentioned. As the toothed rack elements 43 respectively mounted to a hollow profile member 8 are synchronously linearly displaced while being held parallel to each other, then, as shown in Figure 12, they can be fixedly connected together by way of transverse bars 99 for stabilisation thereof.

In the joint 1 at the right in Figure 12 of the group U3 at the right in Figure 12 the multi-function profile member 8 connects the associated motor 5 which is here arranged above to a further individual joint 1. In this case, as indicated in Figure 12A by broken lines, it is provided that the drive shaft 51 driven by the motor 5 passes in a multi-function profile member 8  
 20 through the joint 1 at the right in Figure 12A. It passes through the connection mounting 53 provided at the joint 1 in order to be connected in torque-transmitting relationship to the gear wheel of the downwardly arranged individual joint 1. That individual joint 1 has a linear transmission

(G3) which is concealed here and to which the connected multi-function profile member 8 with the toothed rack element 43 indirectly points.

The joint 1 at the right in Figure 12A of the third group U3 has an inverted worm transmission G3. As described in relation to Figures 2 and 3  
5 in the case of an inverted worm transmission G2 the further transmission element 4 is arranged at the drive output side, is driven by the gear wheel 2 which here is at the drive input side, and is here non-rotatably carried on the multi-function profile member 8, whereby same is also driven. The multi-function profile member 8 thus serves at the same time as a shaft. The multi-  
10 multi-function profile member 8 receives the torque of the motor 5 which here is at the right, the torque being transmitted by way of the inverted worm transmission G2, and couples it by way of the connection mounting 53 into the housing 3 of the downwardly arranged individual joint 1 whereby the joint 1 is rotated about that multi-function profile member 8. The joint 1 at  
15 the left in Figure 12 has a worm transmission G1 driven by the downwardly pointing motor 5. It couples the torque into the housing 3 of the right-hand joint 1 of the third group U3 so that in that way the right-hand joint 1 with the connected motor 5 is rotated about the transmission axis of rotation g.

## List of references

	1	joint
	2	gear wheel
5	21	end
	22	adaptor
	23	side
	24	opening
	25	female thread
10	26	worm gear
	27	male thread
	28	spur gear
	29	external tooth arrangement
	3	housing
15	31	receiving portion
	4	further transmission element
	41	worm
	42	spur tooth arrangement
	43	toothed rack element
20	44	foot
	45	anchor element
	5	motor
	51	drive shaft
	52	motor shaft
25	53	connection mounting
	54	drive shaft portion
	65	clamping element
	651	inner sleeve
	652	outer sleeve

	67	setting unit
	671	adjusting device
	7	bearing
	71	clamping ring
5	72	projection
	73	front bearing
	74	rear bearing
	8	hollow profile member
	81	internal passage
10	82	first receiving groove
	83	first portion
	84	second portion
	85	second receiving groove
	86	third receiving groove
15	87	longitudinal chamber
	9	connecting device
	99	transverse bar
	a	spacing direction
	g	transmission axis of rotation
20	w	operative axis
	B	base
	G	transmission
	G1	worm transmission
	G2	inverted worm transmission
25	G3	linear transmission
	M	manipulator
	Ma	magnetic strip
	R	sensor means
	S	inclined plane

- U1 first group
- U2 second group
- U3 third group
- V connecting device

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## CLAIMS

1. A manipulator comprising at least one multi-function profile member and at least one joint, wherein the at least one multi-function profile member provides a supporting connecting element between two joints of the at least one joint of the manipulator and/or between one joint of the at least one joint of the manipulator and a motor assigned to said joint, wherein the at least one multi-function profile member has a circular outside contour, at least one first receiving groove, a second receiving groove and an internal passage, wherein the at least one first receiving groove and the second receiving groove extend laterally in a longitudinal direction of the at least one multi-function profile member and are configured to open outwardly transversely to the longitudinal direction of the at least one multi-function profile member and wherein at least one additional multi-function profile member is provided and the at least one multi-function profile member and the at least one additional multi-function profile member are at least portion-wise of identical structure at least in respect of their profile configuration,

wherein the at least one joint comprises a gear wheel, which is rotatable about a transmission axis of rotation and arranged in a housing of the at least one joint, and a transmission element, which is arranged in a receiving portion of the housing, wherein the gear wheel and the transmission element form a transmission, the transmission having a drive side and a driven side,

wherein the gear wheel is a worm gear positioned on the driven side of the transmission and the transmission element is a worm positioned on the drive side of the transmission, wherein the worm is arranged non-rotatably on a driveshaft within the internal passage of the at least one multi-function

profile member, wherein the at least one multi-function profile member is attached non-rotatably and non-displaceably to the housing by the first receiving groove, and the at least one additional multi-function profile member is a shaft.

2. A manipulator comprising at least one multi-function profile member and at least one joint, wherein the at least one multi-function profile member provides a supporting connecting element between two joints of the at least one joint of the manipulator and/or between one joint of the at least one joint of the manipulator and a motor assigned to said joint, wherein the at least one multi-function profile member has a circular outside contour, at least one first receiving groove, a second receiving groove and an internal passage, wherein the at least one first receiving groove and the second receiving groove extend laterally in a longitudinal direction of the at least one multi-function profile member and are configured to open outwardly transversely to the longitudinal direction of the at least one multi-function profile member and wherein at least one additional multi-function profile member is provided and the at least one multi-function profile member and the at least one additional multi-function profile member are at least portion-wise of identical structure at least in respect of their profile configuration,

wherein the at least one joint comprises a gear wheel, which is rotatable about a transmission axis of rotation and arranged in a housing of the at least one joint, and a transmission element, which is arranged in a receiving portion of the housing, wherein the gear wheel and the transmission element form a transmission, the transmission having a drive side and a driven side,

wherein the gear wheel is a worm gear positioned on the drive side and the transmission and the transmission element is a worm positioned on the driven side of the transmission, wherein the worm is non-rotatably arranged on the at least one additional multi-function profile member and fixed to it by the second receiving groove, and the at least one additional multi-function profile is a shaft.

3. A manipulator comprising at least one multi-function profile member and at least one joint, wherein the at least one multi-function profile member provides a supporting connecting element between two joints of the at least one joint of the manipulator and/or between one joint of the at least one joint of the manipulator and a motor assigned to said joint, wherein the at least one multi-function profile member has a circular outside contour, at least one first receiving groove, a second receiving groove and an internal passage, wherein the at least one first receiving groove and the second receiving groove extend laterally in a longitudinal direction of the at least one multi-function profile member and are configured to open outwardly transversely to the longitudinal direction of the at least one multi-function profile member and wherein at least one additional multi-function profile member is provided and the at least one multi-function profile member and the at least one additional multi-function profile member are at least portion-wise of identical structure at least in respect of their profile configuration,

wherein the at least one joint comprises a gear wheel, which is rotatable about a transmission axis of rotation and arranged in a housing of the at least one joint, and a transmission element, which is arranged in a receiving portion of the housing, wherein the gear wheel and the transmission element form a transmission, the transmission having a drive side and a driven side,

wherein the gear wheel is a sprocket and the transmission element is a toothed rack element, wherein the toothed rack element is engaged with the first receiving groove, wherein the at least one first receiving groove is open towards the sprocket when the toothed rack element is installed within the first receiving groove; and wherein the at least one additional multi-function profile is a shaft.

4. A manipulator comprising at least one multi-function profile member and at least one joint, wherein the at least one multi-function profile member provides a supporting connecting element between two joints of the at least one joint of the manipulator and/or between one joint of the at least one joint of the manipulator and a motor assigned to said joint, wherein the at least one multi-function profile member has a circular outside contour, at least one first receiving groove, a second receiving groove and an internal passage, wherein the at least one first receiving groove and the second receiving groove extend laterally in a longitudinal direction of the at least one multi-function profile member and are configured to open outwardly transversely to the longitudinal direction of the at least one multi-function profile member and wherein at least one additional multi-function profile member is provided and the at least one multi-function profile member and the at least one additional multi-function profile member are at least portion-wise of identical structure at least in respect of their profile configuration,

wherein the at least one joint comprises a gear wheel, which is rotatable about a transmission axis of rotation and arranged in a housing of the at least one joint, and a transmission element, which is arranged in a receiving portion of the housing, wherein the gear wheel and the

transmission element form a transmission, the transmission having a drive side and a driven side,

wherein each of the at least one multi-function profile members has a transmission type, the transmission type being:

(a) a worm transmission, wherein the gear wheel is a worm gear positioned on the driven side of the transmission and the transmission element is a worm positioned on the drive side of the transmission, wherein the worm is arranged non-rotatably on a driveshaft within the internal passage of the at least one multi-function profile member, wherein the at least one multi-function profile member is attached non-rotatably and non-displaceably to the housing by the first receiving groove, and the at least one additional multi-function profile member is a shaft;

(b) an inverted worm transmission, wherein the gear wheel is a worm gear positioned on the drive side and the transmission and the transmission element is a worm positioned on the driven side of the transmission, wherein the worm is non-rotatably arranged on the at least one additional multi-function profile member and fixed to it by the second receiving groove, and the at least one additional multi-function profile is a shaft; or

(c) a linear transmission, wherein the gear wheel is a sprocket and the transmission element is a toothed rack element, wherein the toothed rack element is engaged withing the first receiving groove, wherein the at least one first receiving groove is open towards the sprocket when the toothed rack element is installed within the first receiving groove; and wherein the at least one additional multi-function profile is a shaft; and

wherein the manipulator comprises more than one multi-function profile member and each of said profile members has either the same transmission type or a combination of the transmission types.

5. The manipulator according to any one of claim 1 to 4, wherein the at least one first receiving groove and the second receiving groove are arranged peripherally at least substantially equally spaced.

6. The manipulator according to any one of claims 1 to 5, wherein one or both of the at least one first receiving groove and the second receiving groove is/are of an undercut configuration.

7. The manipulator according to any one of claims 1 to 6, wherein there are provided two at least one first receiving grooves which are arranged diametrically with each other with respect to a longitudinal axis of the at least one multi-function profile member.

8. The manipulator according to any one of claims 1 to 7, further comprising a third receiving groove for a measuring element.

9. The manipulator according to claim 8, further comprising a fourth receiving groove, wherein the at least one first, second, third and fourth receiving grooves are arranged in mutually crossed relationship with respect to the longitudinal axis of the at least one multi-function profile member, wherein the first receiving groove is arranged diametrically relative to the second receiving groove and the third receiving groove is arranged diametrically with respect to the fourth receiving groove.

10. The manipulator according to any one of claims 1 to 9, wherein the internal passage is of a substantially circular cross-section.

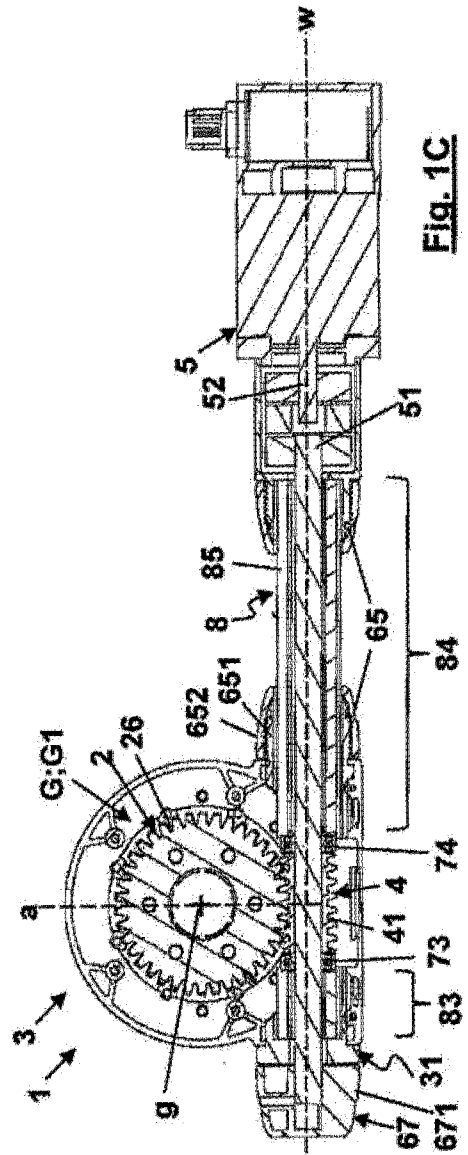
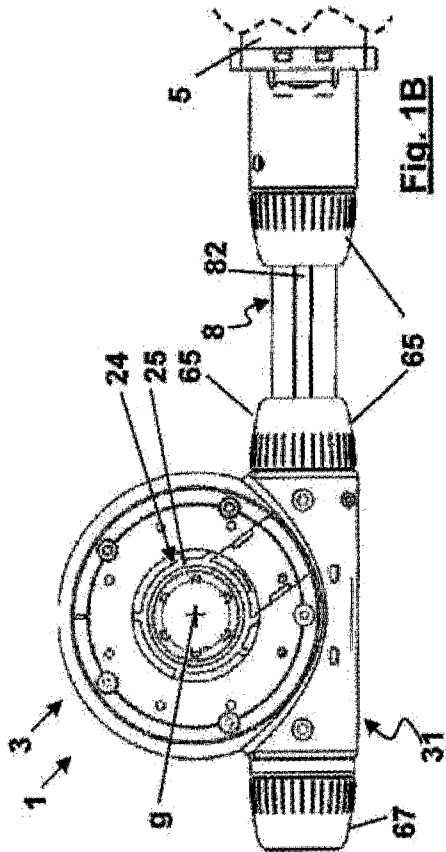
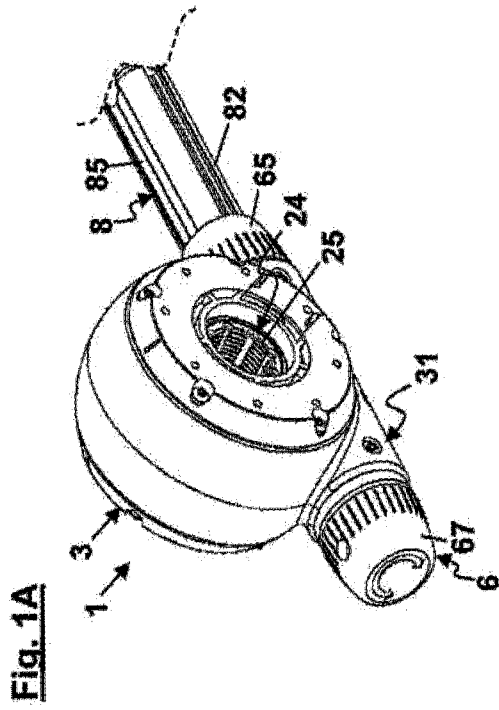
11. The manipulator according to any one of claims 1 to 10, wherein the internal passage has at least one lateral longitudinal chamber configured for one or more of receiving lubricant, passing a line therethrough, and saving on material.

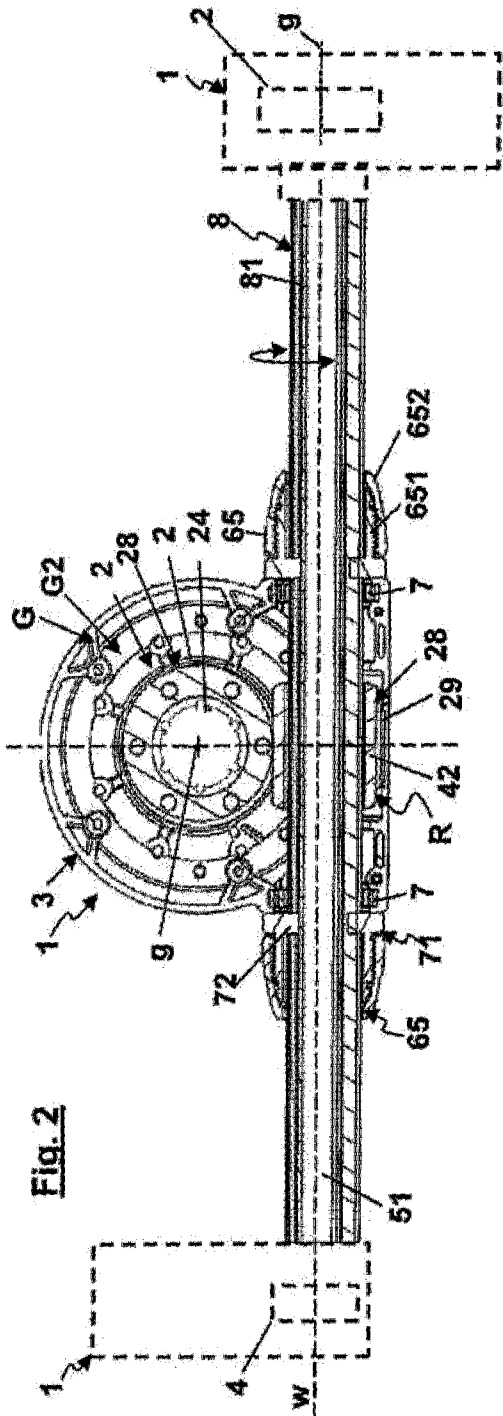
12. The manipulator according to any one of claims 1 to 11, wherein each of the at least one multi-function profile member is respectively connected to the driven side or the drive side of the transmission of the joint respectively associated therewith.

13. The manipulator according to any one of claims 1 to 12, wherein one of the at least one multi-function profile member is connected to the at least one joint at the driven side thereof and another of the at least one multi-function profile member is connected to the at least one joint at the drive side thereof.

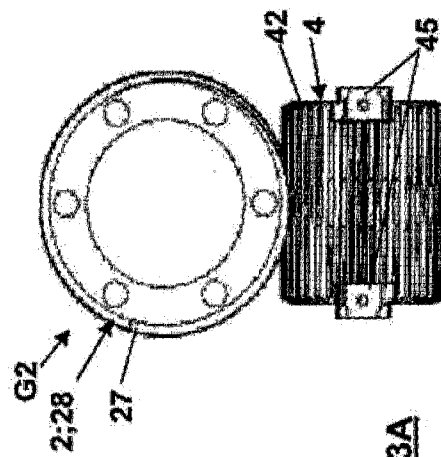
14. The manipulator according to any one of claims 1 to 13, wherein the at least one multi-function profile member is arranged in one or both of the transmission axis of rotation and the operative axis of the respectively associated joint.

15. The manipulator according to any one of claims 1 to 14, wherein the at least one multi-function profile member engages the gear wheel at an end face of the gear wheel.

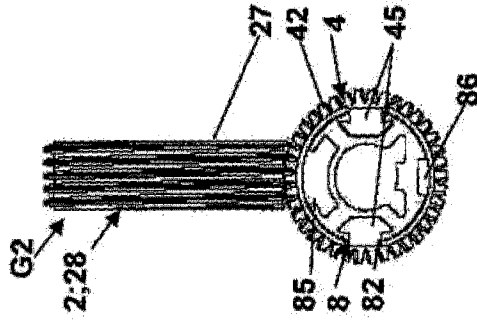




**Fig. 2**

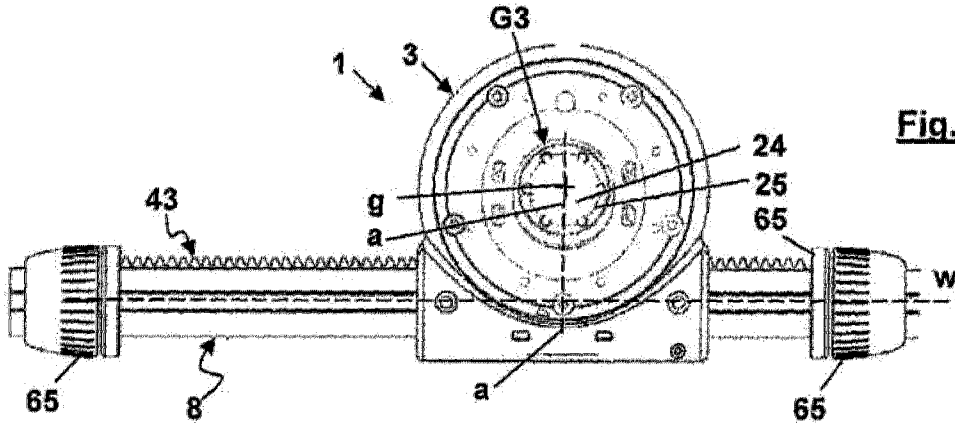


**Fig. 3A**

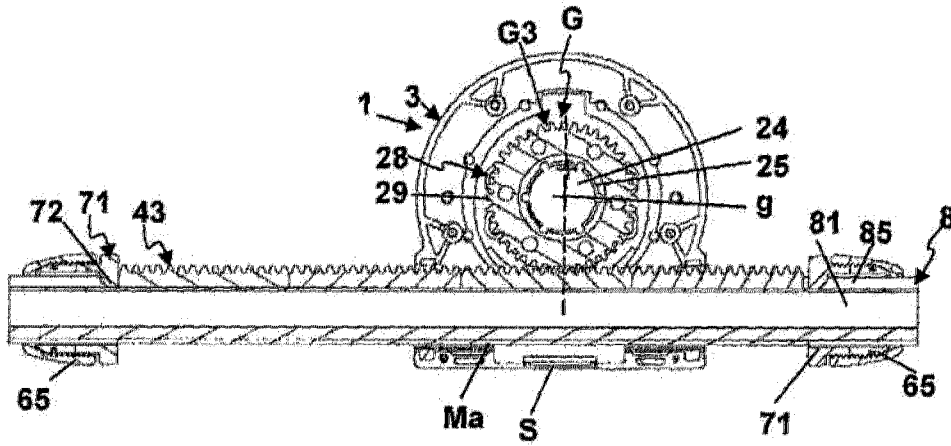


**Fig. 3B**

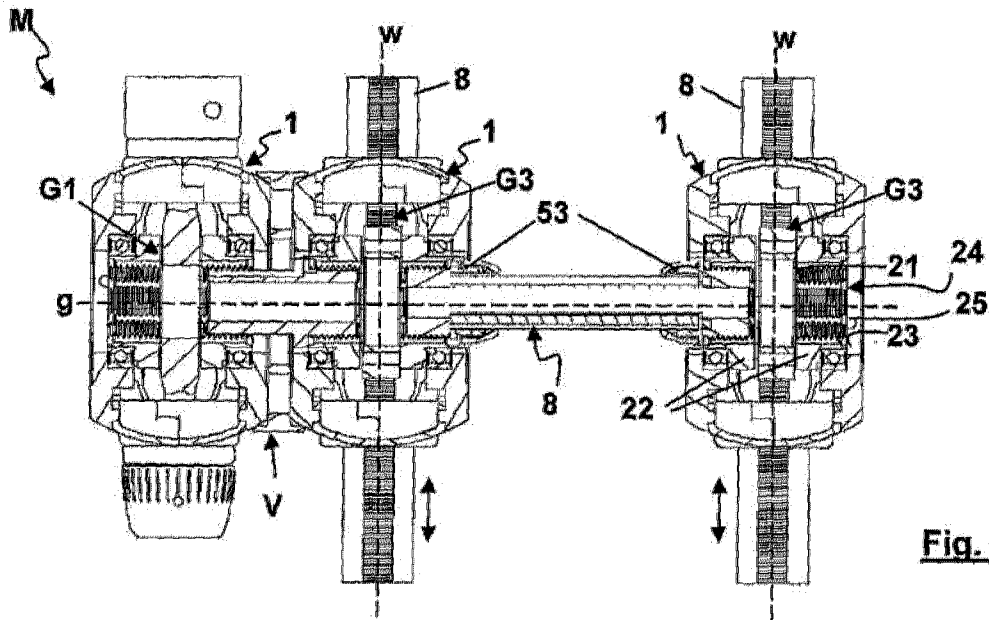
3/8



**Fig. 4A**

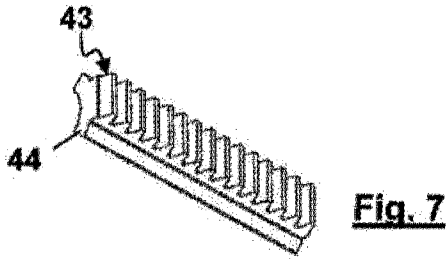
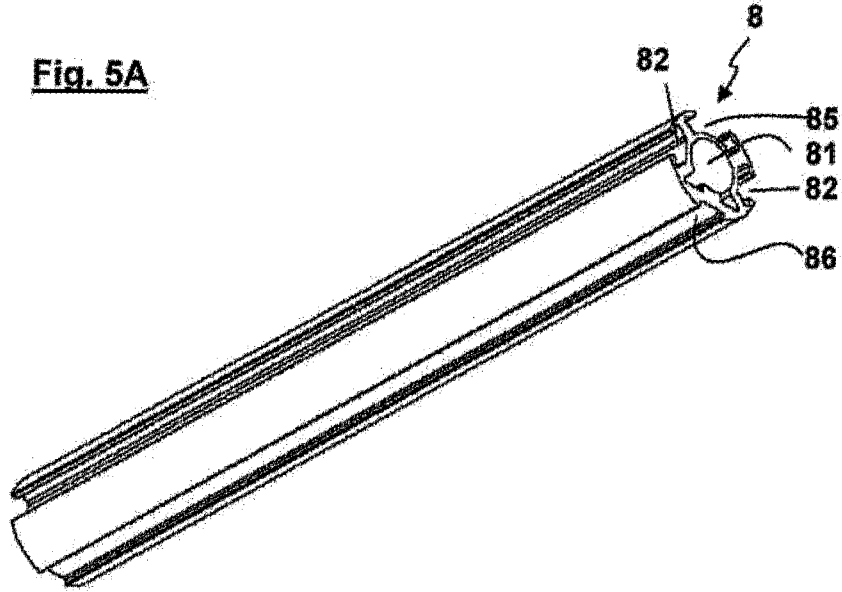


**Fig. 4B**

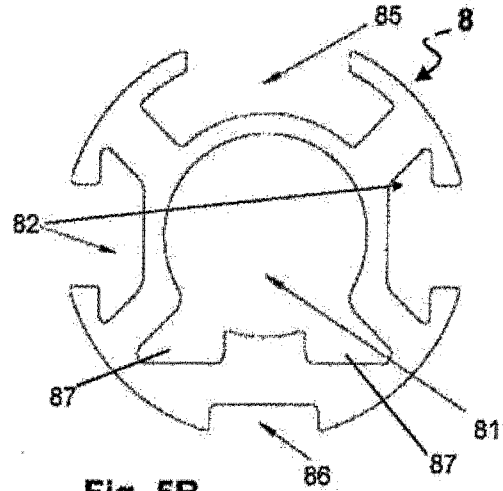


**Fig. 9**

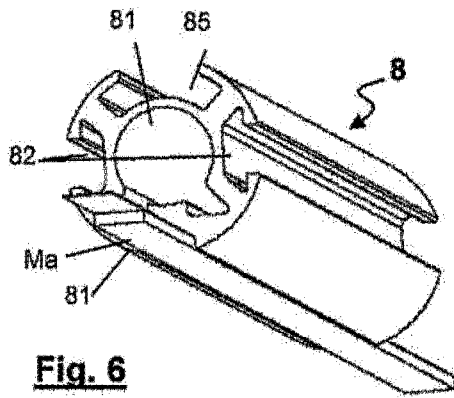
**Fig. 5A**



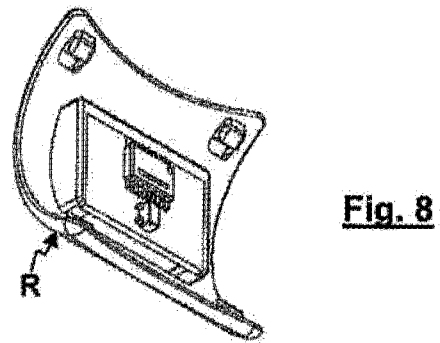
**Fig. 7**



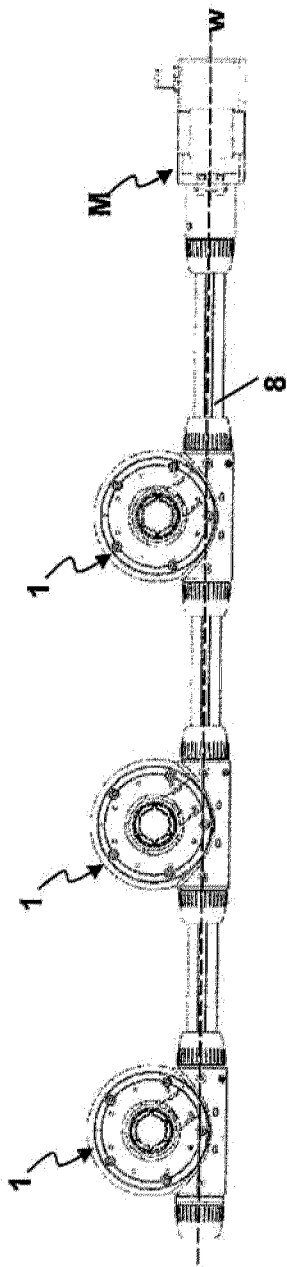
**Fig. 5B**



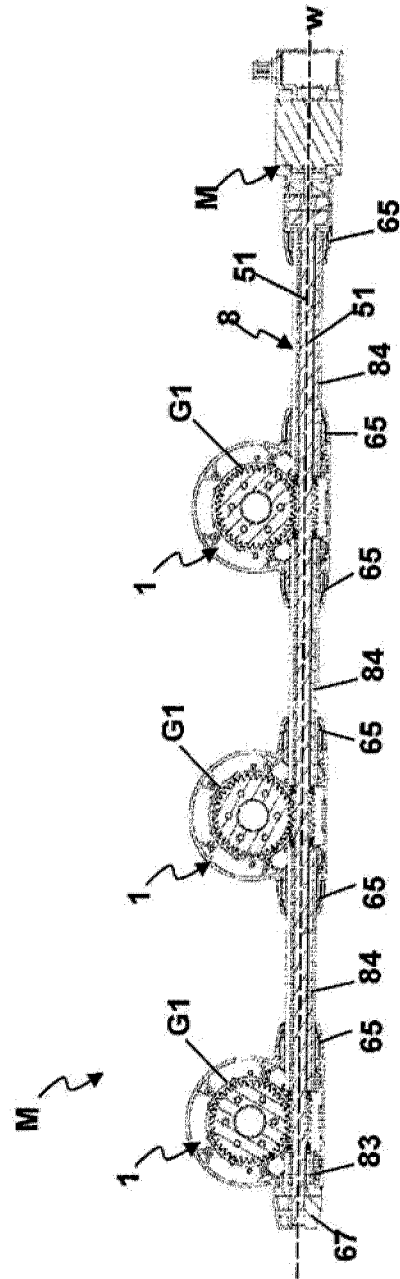
**Fig. 6**



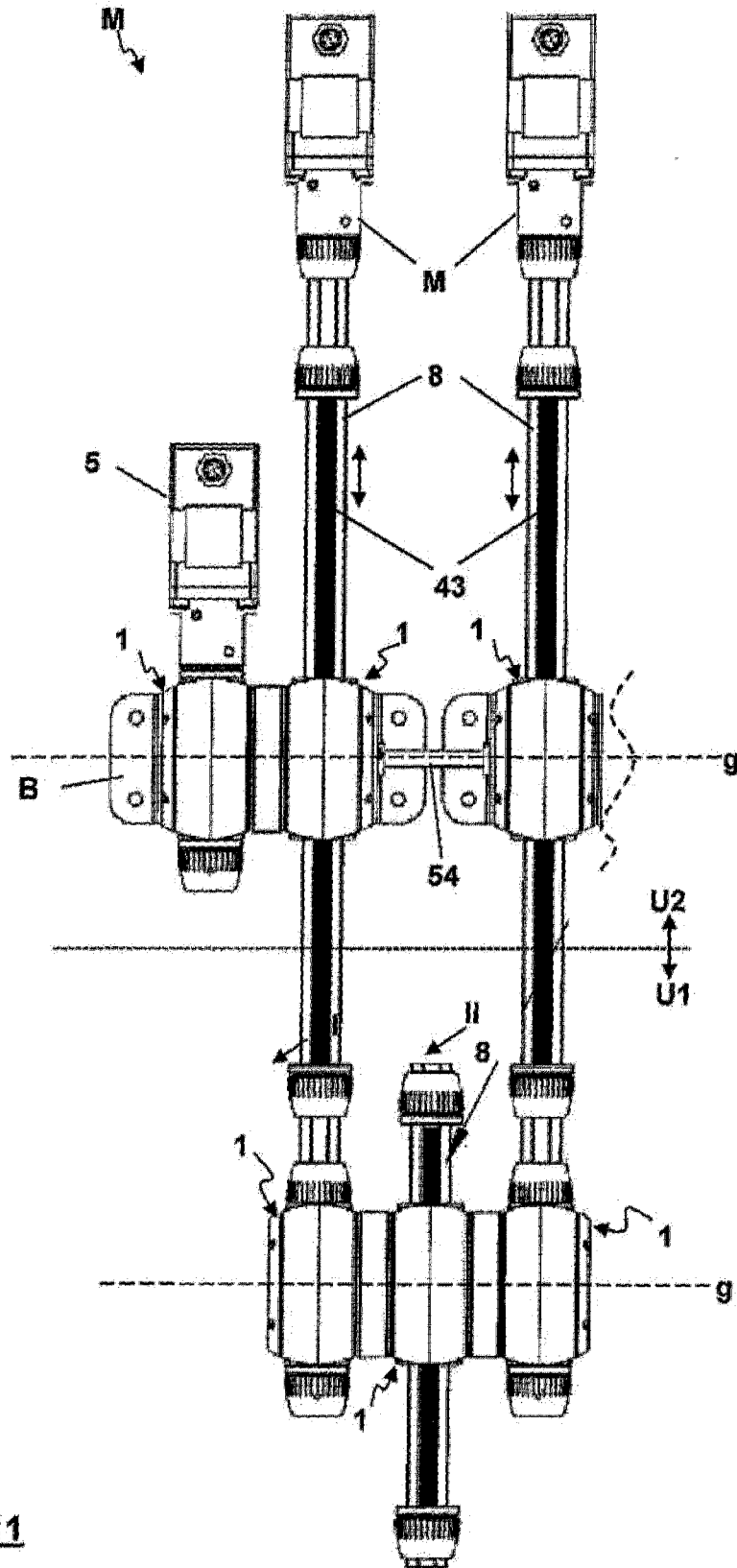
**Fig. 8**



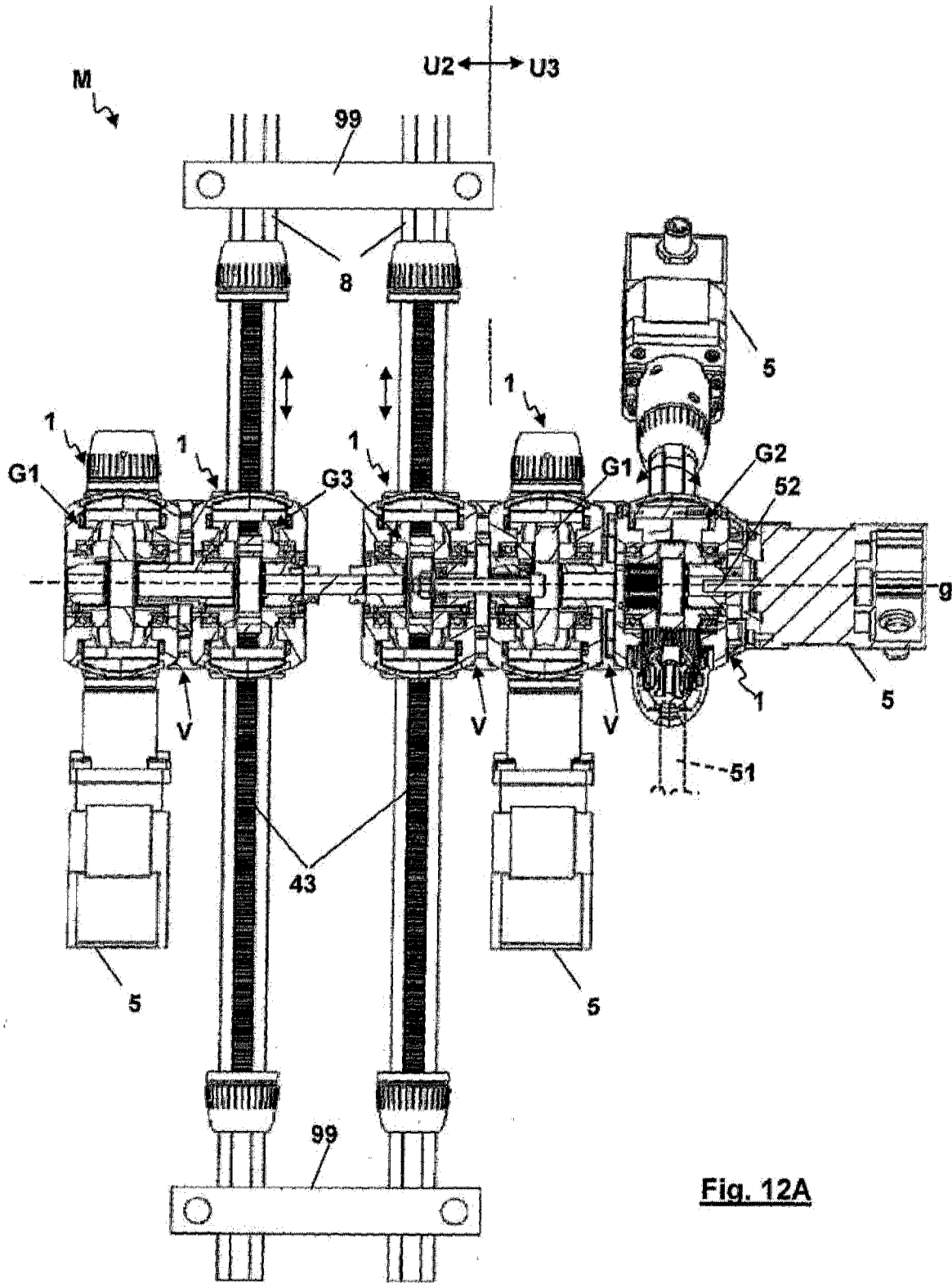
**Fig. 10A**



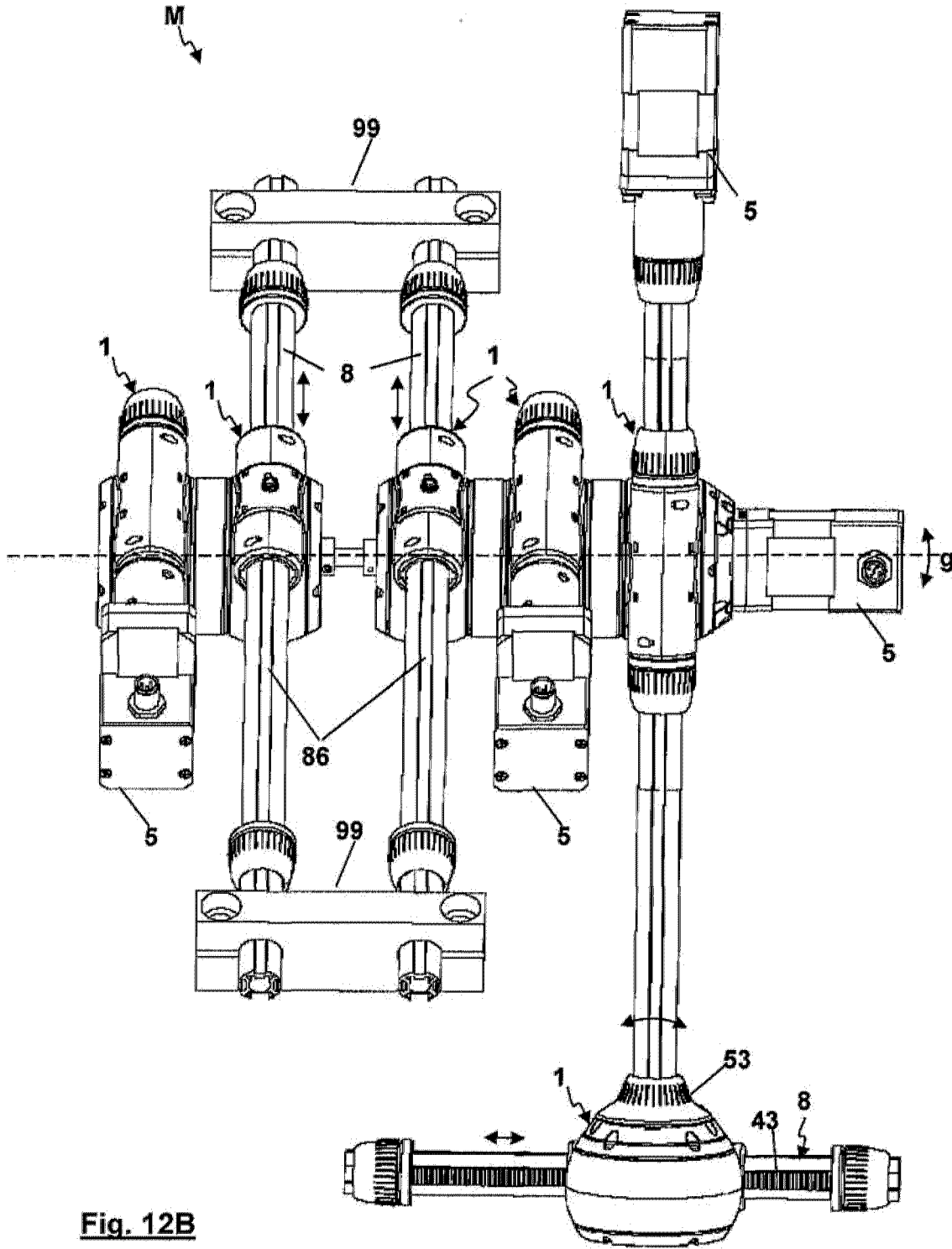
**Fig. 10B**



**Fig. 11**



**Fig. 12A**



**Fig. 12B**

