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DESCRIPTION

Field of the invention

[0001] The invention relates to an apparatus for picking and planting cuttings of plants in a cultivation medium. The invention further relates to a method of picking and planting cuttings of plants in a cultivation medium as well as to a computer readable medium having computer readable instructions stored thereon for performing, when executed by a processor, such a method. The invention also relates to a pick-and-plant head for picking and planting cuttings in a cultivation medium. Furthermore, the invention relates to an apparatus for picking and planting cuttings of plants in a cultivation medium comprising such pick-and-plant head.

Background of the invention

[0002] Nowadays, placing plant cuttings in a cultivation medium is often still done manually. Besides being time consuming, each individual person plants the cuttings in a slightly different way. Furthermore, the position and orientation of the placed cuttings may vary widely as well. As a result, besides being expensive, the propagation success rate of the cuttings can be unreliable.

[0003] US5911631A discusses an apparatus and method for transplanting seedling from a first tray to a second tray.

[0004] Dutch patent publication NL 1012417 describes a method and apparatus for planting cuttings into trays. Cuttings are transported upon a number of conveyor belts. In an example discussed therein, cuttings are angularly oriented in the horizontal plane upon a rotatable disc within an conveyor belt. The oriented cuttings are conveyed to a grab-arm located at the end of the conveyor. The grab-arm in its entirety rotates, and a grab-tip rotates in the opposite direction, whereby the cutting is eventually vertically oriented for placement in a tray.

[0005] Such a device is complex, requiring a plurality of conveyor belts with turntables to orient and gather cuttings for placement. The required positioning of the various components requires a large volume of factory space, both horizontally and vertically. The latter in particular can make operator access difficult. In addition, the coordinated timing of the large number of supply conveyor belts, the rotating grab-arm, and the final product conveyor, is highly sensitive and logistically fragile.

[0006] International publication WO03/022034 describes a method and apparatus for collecting cuttings from a conveyor belt and placing these cuttings in pots. The apparatus includes a pick and place tool on a robot arm, for picking cuttings from the conveyor belt and placing them into pots. The pick and place tool includes a number of vacuum/suction-cup pick-

up means, each for picking up and retaining a cutting from the conveyor belt. The cuttings are initially picked in a horizontal orientation, and after a number of intermediate steps are translated into a vertical orientation with the cut surface downward for planting into a pot.

[0007] The tool furthermore comprises an array of elongate fingers opposing and aligned with the suction cups. These are utilized to create indentations in the cultivation medium of the pots prior to the cuttings being brought into their final orientation and planted.

[0008] The method and apparatus described in WO03/022034 have several disadvantages. For example, the apparatus and method can lead to cutting placement having insufficient uniformity. Although the cuttings are said to be picked up with a predetermined orientation relative to the tool, the sequential picking of adjacent cuttings may cause the orientation of the picked cuttings with respect to the tool to change due to interaction with each other, in particular during the picking process. As a result, some cuttings are placed into the pots with an orientation different from the predetermined orientation, which results in a poorly placed cutting. Furthermore, the pick and place tool may suffer reduced accuracy, a need for greater control, motion and rotation steps, in order to use the indentation fingers.

[0009] European patent publication EP1829446 describes an assembly for placing cuttings in plant plugs in which individual cuttings are gripped by one of the arms of a rotating device by means of low-pressure. The cuttings are then transferred to a belt provided with grippers. This transfer movement takes place continually and in a rotating manner.

[0010] However, the assembly described in EP1829446 has several disadvantages. First, the use of a rotating device for picking individual cuttings occupies a lot of space. Furthermore, the throughput of the assembly is sensitive to logistics failure. The cuttings need to be supplied individually with a spacing between subsequent cuttings, with very narrow tolerances. For example, if the subsequent cuttings are supplied too close together, either one of the cuttings is not processed, or the rotating speed of the rotating device should be adapted, i.e. increased, to allow pick up of both cuttings. The first option would decrease the throughput, whereas the second option complicates control of the rotating device.

[0011] International publication WO2012/101132 describes a method and apparatus for gathering and placing cuttings of plants in a cultivation medium to achieve a predetermined planting pattern. In a method described therein, a number of cuttings are haphazardly distributed upon a generally horizontal conveyer, after which a pattern recognition camera system is used to identify a plurality of individual cuttings from the group, which are suitable to be gathered. A pick up tool is directed to pick up the identified cuttings, its angular orientation in the horizontal plane at each pick up being controlled such that the gathered cuttings are horizontally aligned with their cut stems in a single direction. The gathered cuttings are transferred from the pick up tool into a horizontal cutting holding unit. The cutting holding unit rotates to a vertical orientation with the stems downward and descends to place the cuttings within a cultivation medium. The planting system and the pick-up tool are separate entities.

[0012] Such a method and apparatus offers effective and efficient planting of cuttings, particularly at high capacity throughputs. However, in some circumstances, and for some plant cutting types, such a device may not be optimal.

[0013] The present invention is concerned with addressing one or more the above concerns, and with providing further useful devices and methods for planting cuttings, while at the same time maintaining high levels of effectiveness and efficiency.

Summary of the invention

[0014] It is an object of the invention to provide an apparatus and method for placing plant cuttings in a cultivation medium with excellent performance, in particular with respect to throughput, precision and reliability.

[0015] For this purpose, an aspect of the invention provides a pick-and-plant head for planting plant cuttings in a cultivation medium comprising: a grasper comprising opposed grasping surfaces for grasping a portion of a cutting between them; and an abutment comprising an abutment surface for abutting a cutting, wherein the grasper and abutment are moveable relative to one another and are arranged so that during release of a cutting from the grasper, the abutment passes between the opposed grasping surfaces, and the cutting is abutted by the abutment.

[0016] A pick-and-plant head is a tool-head that carries out both picking and planting of a cutting. Use of a pick-and-plant head is advantageous because during the planting process a cutting is subjected only once to a grasping and release action by the planting apparatus. This limits the number of handlings a cutting undergoes. This can be advantageous in avoiding damage to cuttings (especially for relatively soft plant material) and in avoiding excessive machine complexity required to maintain correct planting orientation of the cuttings when planting.

[0017] A grasper offers excellent orientation control of a cutting, both during pick up, as well as during planting.

[0018] The abutment of the pick-and-plant head preferably comprises a ram having a distal end, wherein a distal end-face of the ram is the abutment surface for the cutting. Such a ram can be of various shapes, but is preferably a wedge or a rod. The distal cutting abutment surface, or the end face, can have any form suitable for abutting a cutting's body or stem. For example, it may be planar or it may be concave, ribbed, or contoured to generally match an abutted surface of a cutting.

[0019] In some embodiments a distal end of the ram has a wedge-shape. This advantageously forms a wedge surface for insertion between the opposed grasping surfaces to force these apart for simple release of a grasped cutting from therebetween.

[0020] Preferably the wedge-shaped ram has a truncated, or angled distal end-face. The distal end face is preferably substantially horizontal when the pick-and-plant head is in a horizontal pick-up orientation. A horizontal pick-up orientation is that orientation of the pick-and-plant head when it is arranged or positioned to pick or grasp a cutting from a substantially horizontal pick-up surface. The end face of the truncated ram is preferably substantially parallel with the planar pick-up surface in the pick-up orientation.

[0021] The grasper of the pick-and-plant head is preferably provided with at least one elongate member, and one of the two opposed grasping surfaces is formed by an inner surface of the elongate member. Preferably the grasper comprises two opposed, elongate members, the two opposed grasping surfaces being provided on the opposed elongate members.

[0022] The grasping surfaces may be inner surfaces of each of the distal ends of the elongate opposed members. Such a configuration may resemble pincers, tongs, tweezers or forceps. Thus the grasper may preferably comprise opposed fingers with substantially flat, distal gripping surfaces. The opposed fingers may be pivoted at a proximal end, or may be held movably in relation to one another for effecting gripping and releasing motions in another manner, such as by movement laterally toward and away from one another.

[0023] Such a grasper offers excellent orientation control of a cutting, both during pick up, as well as during planting. The form of the grasper with elongate members offers the particular advantage that a relatively large portion of the cutting stem can be grasped along at least a part of the elongate member. This provides for an additionally secure grip on the cutting, aiding in accurate orientation for pick-up and planting. This is particularly the case in which the grasper has the form of tongs, forceps, pincers or tweezers

[0024] Each elongate member is preferably a strip, is preferably resiliently flexible, and is preferably formed of plastics or metal, most preferably spring steel, stainless steel or aluminium. A degree of resilient flex within the elongate strip allows for a firm grip upon the cutting without application of excessive force that might damage the stem. The force applied by the grasper upon a cutting can be controlled by pneumatics.

[0025] In a preferred embodiment, the ram is positioned between the elongate members, and the ram and members are moveable relative to one another for axial reciprocation of the ram between the opposed gripping surfaces. As the ram advances, or is inserted between the opposed elongate members, it forces them apart, releasing a cutting held therebetween.

[0026] The pick-and-plant head is further preferably provided with a grasper that is pivotable in a vertical plane. This is such that the head can collect a cutting in a horizontal orientation and rotate it into a substantially vertical orientation ready for planting. Vertical rotations of about 90° are most preferred, but other rotations are possible, for example, from 80° to 100°, depending upon circumstances and cutting type. In an alternative aspect of the invention there is provided a pick-and-plant head for planting plant cuttings in a cultivation medium comprising: a grasper

comprising opposed elongate members with grasping surfaces for grasping a portion of a cutting between them; wherein the grasper is angled from horizontal by from 10° to 80°, preferably from 20° to 70°, and most preferably from 30° to 60°, when the pick-and-plant head is in a pick-up orientation. The elongate members are preferably straight, doglegged or L-shaped

[0027] In a further alternative aspect of the invention, there is provided a pick-and-plant head for planting plant cuttings in a cultivation medium comprising: a grasper comprising opposed grasping surfaces for grasping a portion of a cutting between them; and a spacer arranged to space the grasper from a horizontal cuttings supply surface during a pick up operation.

[0028] The spacer may be positioned adjacent the opposed grasping surfaces. It may also be arranged to space the grasper about 0.1mm or more above the supply surface during a pick-up operation, preferably about 0.15mm or more, and more preferably about 0.2mm or more.

[0029] The spacer is preferably oriented adjacent distal ends of elongate grasping members. Most preferably the spacer has the form of an inverse U and the distal ends of the elongate members are positioned therein when in the pick-up position.

[0030] In a further aspect of the invention there is provided a robotic arm provided with any of the pick-and-plant heads as substantially described herein.

[0031] In a further aspect of the invention, there is provided an apparatus for planting cuttings of plants in a cultivation medium comprising:

a cuttings supply system for supplying a plurality of cuttings;

a camera system for identifying cuttings among the plurality of cuttings provided by the supply system that are suitable for individual pick up by using pattern recognition;

and a robotic arm provided with one or more pick-and-plant heads, wherein said one or more pick-and-plant heads are any of the pick-and-plant heads as described herein.

[0032] The supply surface is preferably substantially horizontal. This aids in a stable dispersion of the cuttings over the supply surface because the cuttings remain stably immobile unless purposefully agitated for dispersion.

[0033] The apparatus may be configured such that the pick-up tool picks up identified cuttings at a predetermined distance from a cutting end to be planted in the cultivation medium depending upon data from one or more images obtained with the camera system.

[0034] Preferably, the apparatus is provided with any of the pick-and-plant heads as described above.

[0035] In general application to the various aspects of the invention, the cuttings supply system comprises a moveable surface for supporting the supplied cuttings. The moveable surface preferably comprises the substantially horizontal supply surface. Use of a moveable surface may aid in spreading the cuttings, and so aid in identification and pick-up of individual cuttings among the plurality of cuttings.

[0036] The moveable surface may be moveable in dependence on one or more images obtained via the camera system. On the basis of the actual placement and orientation of cuttings in the supply system a movement program may be executed for controlling movement of the moveable surface.

[0037] Movement of the surface may be used to haphazardly distribute or disperse the cuttings over the horizontal supply surface. Vibrating, shaking, pulsating, jabbing, wave imparting, and irregular motions may be used to disperse the cuttings. A discussion of various movements and suitable systems are found in international patent publication WO2013/174893, the contents of which is herein incorporated in its entirety by reference.

[0038] In a still further aspect of the invention there is provided a method of planting plant cuttings in a cultivation medium comprising:

providing a scattered plurality of cuttings upon a substantially horizontal supply surface of a cuttings supply system; identifying by way of pattern recognition, at least one cutting amongst the plurality of cuttings as suitable for individual pick up; picking said identified cutting from the supply surface in a substantially horizontal orientation, with a pick-and-plant head on a robotic arm; rotating the picked cutting into a substantially vertical orientation with a plantable end of the cutting facing downward, with the pick-and-plant head; and planting the substantially vertical cutting into a cultivation medium, with the pick-and-plant head; wherein the pick-and-plant head is in accordance with the claims.

[0039] A further embodiment of the method includes the step of agitating the horizontal supply surface to disperse or re-disperse cuttings thereon.

[0040] In a further embodiment of the method the cuttings supply system comprises a conveyor belt, and the conveyor belt comprises the substantially horizontal supply surface.

[0041] In a further embodiment identified cuttings are grasped at a predetermined distance from a plantable end of the cutting, in dependence on one or more images obtained with the camera system.

[0042] In a still further method the cuttings supply system includes an irregularly moveable surface comprising the supply surface, and wherein providing cuttings includes controlling the irregularly moveable surface to disperse or re-disperse cuttings upon the supply surface.

[0043] The apparatus for placing cuttings of plants in a cultivation medium may comprise a computer system comprising a processor with peripherals to enable operation of a method of

planting cuttings as described above. The processor may be connected with one or more memory units which are arranged for storing instructions and data, one or more reading units, one or more input devices, such as a keyboard, touch screen, or mouse, and one or more output devices, for example a monitor. Further, a network Input/Output (I/O) device may be provided for a connection to the networks.

[0044] The processor may comprise several processing units functioning in parallel or controlled by one main processor, that may be located remotely from one another, possibly distributed over the local area network, as is known to persons skilled in the art. The functionality of the present invention may be accomplished by a combination of hardware and software components. Hardware components, either analogue or digital, may be present within the processor or may be present as separate circuits which are interfaced with the processor. Further it will be appreciated by persons skilled in the art that software components that are executable by the processor may be present in a memory region of the processor.

[0045] Embodiments of the method may be stored on a computer readable medium, for example a DVD or USB-stick, for performing, when executed by the processor within the cutting placement apparatus, embodiments of a method placing cuttings of plants in a cultivation medium. The stored data may take the form of a computer program, which computer program is programmed to implement an embodiment of the method when executed by the computer system after loading the computer program from the computer readable medium into the computer system.

Brief description of the drawings

[0046] Various aspects of the invention will be further explained with reference to embodiments shown in the drawings wherein:

FIG. 1 shows an elevated view of an apparatus for placing plant cuttings in a cultivation unit according to an embodiment of the invention;

FIG. 2 shows a side view of a pick-and-plant head in a pick-up position;

FIG. 3 shows an alternative view of the pick-and-plant head of figure 1, from the front and side;

FIG.4 shows an enlarged view of a part of the pick-and-plant head of figure 3;

FIGS.5a-c show elongate grasper members;

FIG.6 shows a ram;

FIG.7 shows an embodiment similar to that of FIG.4 including a spacer;

FIGS.8a-j show pick and plant stages using the pick-and-plant head of FIG.1.

Description of illustrative embodiments

[0047] The following is a description of various embodiments of the invention, given by way of example only and with reference to the drawings.

[0048] FIG. 1 shows an apparatus **1** for planing cuttings of plants in a cultivation medium.

[0049] The plant cuttings may be cuttings of any sort, and may include cuttings having a stem and one or more leaves, further referred to as stem cuttings, cuttings predominantly consisting of leaves, further referred to as leaf cuttings, as well as cuttings having a tuber or root, further referred to as tuber or root cuttings. Examples of stem cuttings include, but are not limited to, cuttings of chrysanthemum, Christmas star, boxwood, flamingo flower ('anthurium'), and panda plant ('kalanchoe'). Examples of leaf cuttings include, but are not limited to, cuttings of crab cactuses, and conifer. Examples of tuber or root cuttings include, but are not limited to cuttings of cranesbill ('geranium').

[0050] The apparatus **1** comprises a cuttings supply system **10** for supplying a plurality of cuttings **2**. The cuttings supply system **10** may comprise a cuttings inlet for supply of cuttings **2** to the cuttings supply system **10**.

[0051] In the shown embodiment, the cuttings **2** may be placed onto the cuttings supply system **10** via an opening, either manually by a human operator or automatically, for example via a conveyor belt.

[0052] Preferably, the cuttings supply system **10** takes the form of a container having side walls **12** and a cuttings supply surface **14**. The cuttings supply surface **14** supports the cuttings. The shown cuttings supply surface **14** is horizontal, and this provides for a stable distribution of the cuttings over the surface. Supply surfaces angled slightly from horizontal are possible and may still provide a stable distribution, but are not preferred. The side walls **12** ensure that the cuttings are kept within the container. A container occupies little space, which makes the apparatus **1** compact. Additionally, movement and/or instalment of the apparatus **1** may be easy as well.

[0053] The cuttings supply surface **14** may be, at least partially, moveable. For example, the cuttings supply surface **14** may be mechanically agitated or excited to haphazardly distribute or disperse the cuttings over the horizontal supply surface. Such movements may include vibrating, shaking, pulsating, jabbing, wave impartation, and irregular motions. In a typical scenario, cuttings **2** are provided to the cuttings supply surface **14** in a bulk or mass by a human operator or by a conveyor belt. The cuttings supply surface **14** is then agitated or excited as discussed above so that the individual cuttings **2** are disentangled from the delivered bulk or mass of cuttings **2** and are spread out over the cuttings supply surface **14**.

[0054] Disentanglement and disbursement of the cuttings **2** is advantageous in aiding pick-up of individual cuttings **2** from the cuttings supply surface **14** as discussed in further detail below.

[0055] The cuttings supply surface **14** preferably comprises a flexible, sheet of material held under tension. Examples of such materials are found in conveyor belt systems for transporting cuttings. A flexible sheet of material is susceptible to prodding and shaking to give the discussed distribution movements.

[0056] The cuttings supply surface **14** may be implemented as a conveyor belt upon which cuttings are conveyed toward a pick-up zone, within which a pick-and-plant tool **30** can pick.

[0057] The apparatus further comprises a camera system **20** for identifying individual cuttings **2** among the plurality of cuttings provided by the supply system **10** that are suitable for individual pick up. The camera system **20** comprises one or more cameras **22**. Based on images obtained with the one or more cameras **22**, cuttings that are suitable for individual pick up are identified using pattern recognition techniques. For example, in the case of stem cuttings, the camera system **20** may be arranged to identify individual stems based on the recognition of a pattern corresponding to an individual stem of a stem cutting lying on the cuttings supply surface **14**. The images provided by the camera system **20** may be any type of suitable image including 2-dimensional images and 3-dimensional images. In the case of 3-dimensional imaging, the camera system **20** generally includes more than one camera **22**.

[0058] The apparatus further comprises a pick-and-plant tool **30**. The pick-and-plant tool **30** is communicatively coupled to the camera system **20**. The pick-and-plant tool **30** is arranged for picking up cuttings **2** identified by the camera system **20** from among the plurality of cuttings **2**, and planting the picked cuttings **2** directly into a plant cultivation medium **4**.

[0059] The shown pick-and-plant tool **30** is provided with a robot arm **32** and a pick-and-plant head **34**.

[0060] The pick-and-plant head is discussed in more detail in relation to figures 2 to 7.

[0061] The robot arm **32** is preferably provided with a number of degrees of freedom to position and orient the pick-and-plant head for pick up, transport, and planting of picked-up cuttings into the cultivation medium **4**.

[0062] In some applications a robot arm **32** having 4 degrees of freedom is provided, i.e. 3 rotation axes, where one axis is arranged to allow transfer along the axis (preferably in a direction substantially perpendicular to the bottom surface of the cuttings supply system) is sufficient. In alternative applications a more sophisticated robot arm **32** is provided, for example a robot arm **32** capable of picking up cuttings in a variety of three-dimensional (3D) orientations using 3D-images. These more sophisticated robot arms **32** may be arranged to operate with 6 degrees of freedom.

[0063] The robot arm **32** is programmed to move the pick-and-plant head **34** to a selected cutting **2** on the cuttings supply surface **14** of the cuttings supply system **10**, and to position the pick-and-plant head **34** into a suitable orientation to grasp, i.e. pick, a cutting **2**. For this purpose, the cutting position (for example using Cartesian-coordinates, as will be understood by a person skilled in the art) and the orientation of the cutting are obtained using images from the camera system **20** in combination with pattern recognition.

[0064] Once the pick-and-plant head **10** has grasped the desired cutting **2**, the robot arm **32** is programmed to move the pick-and-plant head **34** along with the grasped cutting **2** to planting coordinates within a plant cultivation medium **4**, where the cutting is then planted into the medium. The specific details of the action of the pick-and-plant head **34** is discussed in greater detail in relation to figures 2 to 8j.

[0065] The apparatus **1** may further comprise a cultivation medium supply unit **54** for supplying the cultivation medium. The cultivation medium may be provided in a predefined format, for example in the form of soil cubes with suitable dimensions (e.g. length x width x height of 40 mm x 40 mm x 30 mm), or in plant pots. The cultivation medium may be any medium suitable for cultivating cuttings. Examples of suitable cultivation media include but are not limited to a soil block, a soil cube, rock wool, and flower soil.

[0066] The cultivation medium supply unit **54** preferably takes the form of a conveyor belt **56**. The conveyor belt **56** is readily aligned with the pick-and-plant tool **30**.

[0067] An indentation unit (not shown) may be provided to pre-indent the cultivation medium to create recesses in which the cuttings may be placed by the pick-and-plant tool **30**. Such an indentation unit is arranged for indenting the cultivation medium before planting i.e. it makes holes of suitable size and shape to accommodate a cutting to be planted, at the planting location. The use of an indentation unit can offer safe insertion of cuttings **2** into the cultivation medium **4**. For example, when a cutting **2** is inserted into a preformed indentation rather than a closed surface of medium **4**, it is not subjected to forces associated with shunting cultivation medium. The planting of cuttings can thus be done with less force, which reduces the risk of damaging the cuttings during planting. However, such an additional process step and equipment requirement can be disadvantageous, and according to some advantageous embodiments of the invention an indentation unit is not provided.

[0068] If present, the indentation unit may be arranged to indent the cultivation medium before the pick-and-plant head **34** plants the cuttings therein. Alternatively, the cultivation medium **4** may be prepared with indentations by a separate apparatus upstream in the process. In both cases the robot arm **32** of the pick-and-plant tool **30** is programmed to bring the pick-and-plant head **34** to the location of the indentations when planting a cutting.

[0069] In a preferred embodiment, discussed in more detail below, no indentation unit is provided. Rather the pick-and-plant head **34** simultaneously indents the cultivation medium while planting a cutting **2**.

[0070] FIGS. 2 to 4 show views of an embodiment of a pick-and-plant head **34** for attachment to a robot arm **32** via a connector **35**. The pick-and-plant head **34** is provided with a grasper **36** arranged for picking up a cutting **2**. The shown grasper is particularly suitable for grasping the stem of a stem cutting **2**. Stem cuttings typically include a stem portion with an end that serves as a basis for roots to be formed, and a leaf portion arranged for developing plant elements such as leaves, buds and flowers.

[0071] The grasper **36** comprises two opposed elongate members **38a**, **38b**. The elongate members **38a**, **38b** are generally blade shaped strips, and extend from a proximal end to a distal end. A single elongate member **38a** is shown in figure 5a. The elongate members **38a**, **38b** are adjoined to the body of the pick-and-plant tool **34** at their proximal ends and converge with one another toward their distal ends so as to form forceps or pincers for grasping a cutting **2**.

[0072] Each elongate member **38a**, **38b** is provided on an inner surface of its distal end with a grasping surface **40** for grasping the stem of the cutting **2**. The grasping surface as shown is substantially flat, but may be contoured or ribbed to aid in grasping the stem of the cutting **2**.

[0073] The elongate members **38a**, **38b** are preferably resiliently flexible transverse to the grasping direction. Such resilient flex allows for a firm grasp of the stem of the cutting, while at the same time avoiding an excessively forceful clamping that might damage a cutting **2**. Forming the elongate members from resiliently flexible plastics or metals can achieve this flex. The elongate members **38a**, **38b** preferably comprise spring steel, stainless steel, aluminium, or aluminium alloys in this respect.

[0074] The elongate members **38a**, **38b** are movable transversely toward and away from one another. This is achievable by opposing movement of the attachment blocks **42a**, **42b** to which the elongate members **38a**, **38b** are respectively joined at their proximal ends. By movement of the attachment blocks **42a**, **42b** toward one another, the grasping surfaces **40** are brought together and grasp upon the stem of cutting **2**. It will be clear to the skilled reader that the elongate members **38a**, **38b** could be brought together by other movements. For example, the elongate members **38a**, **38b** could be hinged to one another at a distal position, and pivoted toward and away from one another for grasping and releasing respectively.

[0075] The grasper **36** of the pick-and-plant head **34** is pivotable about an axis **44** such that it can translate from a generally horizontal pick-up position as shown in figures 2 to 5, to a substantially vertical planting position shown in figures 8d to 8g.

[0076] In the pick-up position, the elongate members **38a**, **38b** are arranged to grasp a cutting **2** that is in a substantially horizontal orientation upon the cuttings supply surface **14**.

[0077] In the planting position, the elongate members **38a**, **38b** are arranged to hold a cutting substantially vertically with its cut or rooting end downward, in order to insert, and so plant, the

cutting **2** into the cultivation medium **4**. In the planting orientation, the orientation of the cuttings is a substantially vertical orientation with the stem portion facing downwards.

[0078] In the shown embodiments, the cutting is rotated about 90° to bring the cutting from a horizontal position to a vertical position for planting. However, the rotation may also, for example, be from 80° to 100°, depending upon circumstances and cutting type.

[0079] In the shown embodiment, pivoting of the pick-and-plant head **34** about axis **44** is achieved by way of an extensible and retractable pneumatic arm **48**.

[0080] As shown in figure 2, the grasper **36** is preferably angled compared to the cuttings **2**. That is, in the pick-up position, the grasper is angled from horizontal by an angle alpha. Angle alpha is preferably 10° to 80°, preferably from 15° to 70°, and most preferably from 25° to 60°, when the gripper head is in the pick-up orientation. In figure 2 angle alpha is about 30°. Providing the grasper **36** at an angle allows for the horizontal cutting to be firmly grasped at its cut or root end, while avoiding damage to any leaves present at the top of the cutting. In addition, the angled grasper **36**, once rotated into the vertical planting position, offers vertical support to the cutting **2**, that is, along the stem axis, so that upon insertion into the cultivation medium **4** the elongate members **38a**, **38b** are able to form a scaffold about the stem supporting it and avoiding damage thereto upon insertion.

[0081] As discussed above, in some circumstances the apparatus may be provided with an apparatus for pre-indenting the cultivation medium **4**. However, it is an advantage of a preferred embodiment of the present invention that the grasper **36** of the pick-and-plant head **34** is such that no advance indentation of the cultivation medium **4** is required. This is at least partially achieved through the parallel support offered by the elongate members **38a**, **38b**.

[0082] In a most advantageous scenario, this reduces or overcomes the need to pre-indent the cultivation medium with cavities to accept cuttings. This reduces the number of steps needed to complete planting since no additional indentation step is required. It also reduces complexity in alignment, because the indentation is made simultaneously with placement of the cutting, meaning there is no requirement to detect indentation positions with a camera system, or to accurately align either the pick-and-plant head with indentations, or to align indentations in relation to the other components of the system. In addition, such direct insertion may provide a snugger contact of the cultivation medium about the cutting stem, than is achieved by pre-indentation. This is because pre-indentation may create indents with a too great a diameter for a particular cutting, taking into account that a standard indentation size is used which is large enough for expected stem sizes and accuracy tolerances in placement. A snugger fit within the cultivation medium can provide improved rooting and nutrient uptake for a cutting, as well as physical orientation.

[0083] To offer maximum support, a cutting **2** is grasped by the elongate members **38a**, **38b** close to its cut or root surface. The distal ends of the elongate members **38a**, **38b** are then at least partially inserted into the cultivation medium **4** along with the cut or root end of the cutting

2 at the planting stage. The tips of the elongate members **38a**, **38b** in this manner buttress the stem and provide the rigidity to push aside cultivation medium **4**, in effect simultaneously indenting the cultivation medium and planting.

[0084] The distal ends of the elongate members **38a**, **38b** are provided with truncated or angled end faces **41a**, **41b** such that these are substantially parallel with the cuttings supply surface **14** when the pick-and-plant head **34** is in the pick-up configuration. The end faces **41a**, **41b** are thus preferably substantially horizontal when the pick-and-plant head **34** is in a horizontal pick-up configuration. This provides an extended grip area upon the cutting **2** as well as a generally blunt, low damage interface with the cuttings supply surface **14**.

[0085] The pick-and-plant tool **30** may use one or more images obtained with the camera system **20** to determine at what position a specific individual cutting should be picked up to enable suitable placement in the planting unit. Determining the desired position of pick-up can be done by analysis using pattern recognition algorithms known to those skilled in the art.

[0086] While the shown embodiments make use of straight elongate members (as shown in figure 5a) angled from horizontal, a similar effect in terms of picking-up and planting could be readily achieved by way of a dogleg or L-shape as shown in figures 5b and 5c respectively. Such alternative forms are also considered to be angled within the meaning of this document, the angle being the effective angle of inclination above the cutting in the pick-up orientation.

[0087] The pick-and-plant head **34** may also be provided with a ram **50**. The functioning of the shown ram **50** will be more fully discussed in relation to figures 8a-j below. Fig. 6 shows the ram **50** in greater detail.

[0088] A function of the ram **50** is to abut the body of the cutting **2** at the stage of planting when the elongate members **38a**, **38b**, are withdrawn from, or release, the cutting **2**. The cutting abuts against the distal end face **52** of the ram **50** during its release from the pick-and-plant head **34** into the cultivation medium **4**. In this manner the cutting **2** is secured in place in the desired planting orientation, while allowing simple release from the grasper **36**.

[0089] The end face of the ram **50** is preferably angled or truncated similarly to the elongate members **38a**, **38b**. The surface of the ram end face **52** can have any form suitable for abutting a cutting body. For example, it may be planar, as illustrated, or it may be concave, ribbed, or contoured to generally match an abutted surface of a cutting **2**.

[0090] Furthermore, the illustrated ram **50** may function to force apart elongate members **38a**, **38b** during a planting step. The ram **50** is in this respect positioned between the elongate members **38a**, **38b**, and the elongate members **38a**, **38b** can be forced apart either by retraction over the ram **50**, or by forward insertion of the ram **50** therebetween. The ram **50** is generally wedge shaped, being the inverse of the inner surfaces of the elongate members **38a**, **38b**. Other forms achieving the same function can be contemplated, such as a rod-shaped ram.

[0091] Generally, the pick-and-plant tool **30** is programmed to assume that the cuttings supply surface **14** is at substantially the same vertical level throughout the supply system **10**. However, to ensure that local deviations from such average level do not jeopardize the performance of the pick-and-plant head **34**, a surface detection sensor may be provided. In such case, the grasper **36** of the pick-and-plant head **34** may be activated for grasping upon detection of the surface.

[0092] In an alternative embodiment, shown in figure 7, a spacer **46** is provided, which abuts the surface of the cutting supply surface **14** ahead of the distal ends of elongate members **38a**, **38b**. The spacer **46** has a lower surface that is preferably at least 0.1mm lower than the lowest point of the elongate members **38a**, **38b** when the pick-and-plant head **34** is in the pick-up position shown in figure 5. This aids in preventing the distal tips of the elongate members **38a**, **38b** from coming into contact with the cuttings supply surface **14**, and as such can help to reduce abrasion of the supply surface **14** that might otherwise result from scraping of the tips of the elongate members **38a**, **38b** across it as they are brought toward one another during grasping.

[0093] Turning to FIGS. 8a-8j a number of different orientations of the pick-and-plant head **34** during the picking and planting process are shown to illustrate a method of picking and planting a cutting **2**.

[0094] As discussed above, the pick-and-plant head **34** is carried upon the distal end of a robot arm **32** which transports the pick-and-plant head **34** between picking and planting positions, and vice versa. First, the robot arm **32** moves the pick-and-plant head **34** towards an identified single cutting on the basis of information obtained with the camera system **20**. The elongate members **38a**, **38b** of the grasper are in an open state, i.e. when the elongate members **38a**, **38b** are open to accept a cutting therebetween. FIGS. 4, 8a and 8b show the grasper in an open state.

[0095] As illustrated in FIG. 8a, the robot arm **32** brings the pick-and-plant head **34** into the region of a selected cutting **2** in an orientation ready for picking it, that is, with the distal ends of the elongate members **38a**, **38b** aligned with and facing in the direction of the cut end of the cutting **2**.

[0096] In FIG. 8b the pick-and-plant head **34** is positioned with a suitable portion of the cutting **2** between the grasping surfaces **40**. The selected portion of the shown stem cutting **2** is close to or at the cut end of the stem.

[0097] Moving to FIG. 8c, the attachment blocks **42**, and thus also the elongate members **38a**, **38b** as a consequence, are moved toward one another, for example by pneumatics. The grasping surfaces **40** come to bear upon the stem of the cutting so that it is securely grasped.

[0098] The robot arm **32** then moves the pick-and-plant head **34** along with the grasped

cutting **2** away from the cuttings supply surface into an open volume where the grasper **36** is rotated 90° about axis **44** translating the cutting **2** from a generally horizontal orientation to a generally vertical orientation with its cut end disposed downwardly ready for insertion into a cultivation medium **4**, as shown in FIG. 8d.

[0099] The robot arm simultaneously, or thereafter, positions the pick-and-plant head at pre-planting coordinates above a plant cultivation medium **4**, figure 8e.

[0100] As shown in FIG.8f, the pick-and-plant head descends to plant the cutting **2** within the cultivation medium **4**. The distal ends of the elongate members **38a**, **38b** also penetrate the cultivation medium and so support the cutting **2** against insertion forces that might otherwise damage it.

[0101] In FIG.8g, the ram **50** is advanced toward the cutting **2** to abut with its end face **52** against it, securing the cutting within the cultivation medium **4**.

[0102] In FIG.8h, the elongate members **38a**, **38b** are proximally retracted. As they retract their inner surfaces engage with the wedged ram **50** such that the elongate members are forced laterally apart to release the cutting **2** from the grasper **36**.

[0103] Finally, the pick-and-plant head **34** is carried away from the cutting by the robot arm **32**, FIG. 8i, and planting of the cutting within the cultivation medium **4** is complete, FIG.8j.

[0104] The above steps are repeated to plant further cuttings, either within the same container as the first cutting, or in further containers.

[0105] In an alternative embodiment, not shown, the pick-and-plant tool **30** may be arranged for simultaneous picking and planting of a plurality of cuttings **2** in a cultivation medium **4**. In such an embodiment, the pick-and-plant head **34** is provided with a plurality of graspers, each for grasping a single cutting **2**, whereby a number of cuttings can be collected and then simultaneously planted in the plant cultivation medium **4**.

[0106] The invention has been described by reference to certain embodiments discussed above. It will be recognized that these embodiments are susceptible to various modifications and alternative forms well known to those of skill in the art without departing from the spirit and scope of the invention. Accordingly, although specific embodiments have been described, these are examples only and are not limiting upon the scope of the invention, which is defined in the accompanying claims.

REFERENCES CITED IN THE DESCRIPTION

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

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Krav

1. Et pluk-og-plant-hoved (34) til plantning af stiklinger (2) i et dyrkningsmedium (4), som omfatter;
 - 5 a. en griber (36), der omfatter modstående gribeflader (40) til at gribe en del af en stikling mellem dem; og
 - b. et vederlag, der omfatter en vederlagsflade til vederlag af en stikling, hvori griberen og vederlaget kan bevæges i forhold til hinanden og er arrangeret, så vederlaget under frigivelse af en stikling fra griberen passerer
10 mellem de modstående gribeflader, og stiklingen understøttes af vederlaget.
2. Et pluk-og-plant-hoved (34) i henhold til krav 1, hvor vederlaget omfatter en støder (50), der har en distal ende, hvori en distal endeflade (52) på støderen er vederlagsfladen til stiklingen; fortrinsvis hvori en distal ende af støderen har en
15 kileform.
3. Et pluk-og-plant-hoved (34) i henhold til krav 2, hvori den distale ende af støderen (50) har en kileform, der er tilspidset, fortrinsvis med en distal endeflade (52), der er hovedsagelig plan eller forsænket.
20
4. Et pluk-og-plant-hoved (34) i henhold til ethvert af kravene 2 til 3, hvori den distale kileformede ende af støderen (50) er tilspidset i en vinkel, så den er hovedsagelig vandret, når pluk-og-plant-hovedet er i en stiklingsopsamlingsposition.
25
5. Et pluk-og-plant-hoved (34) i henhold til ethvert af kravene 2 til 4, hvori de modstående gribeflader (40) er arrangeret til at bevæge sig væk fra hinanden, når støderen (50) indføres derimellem.

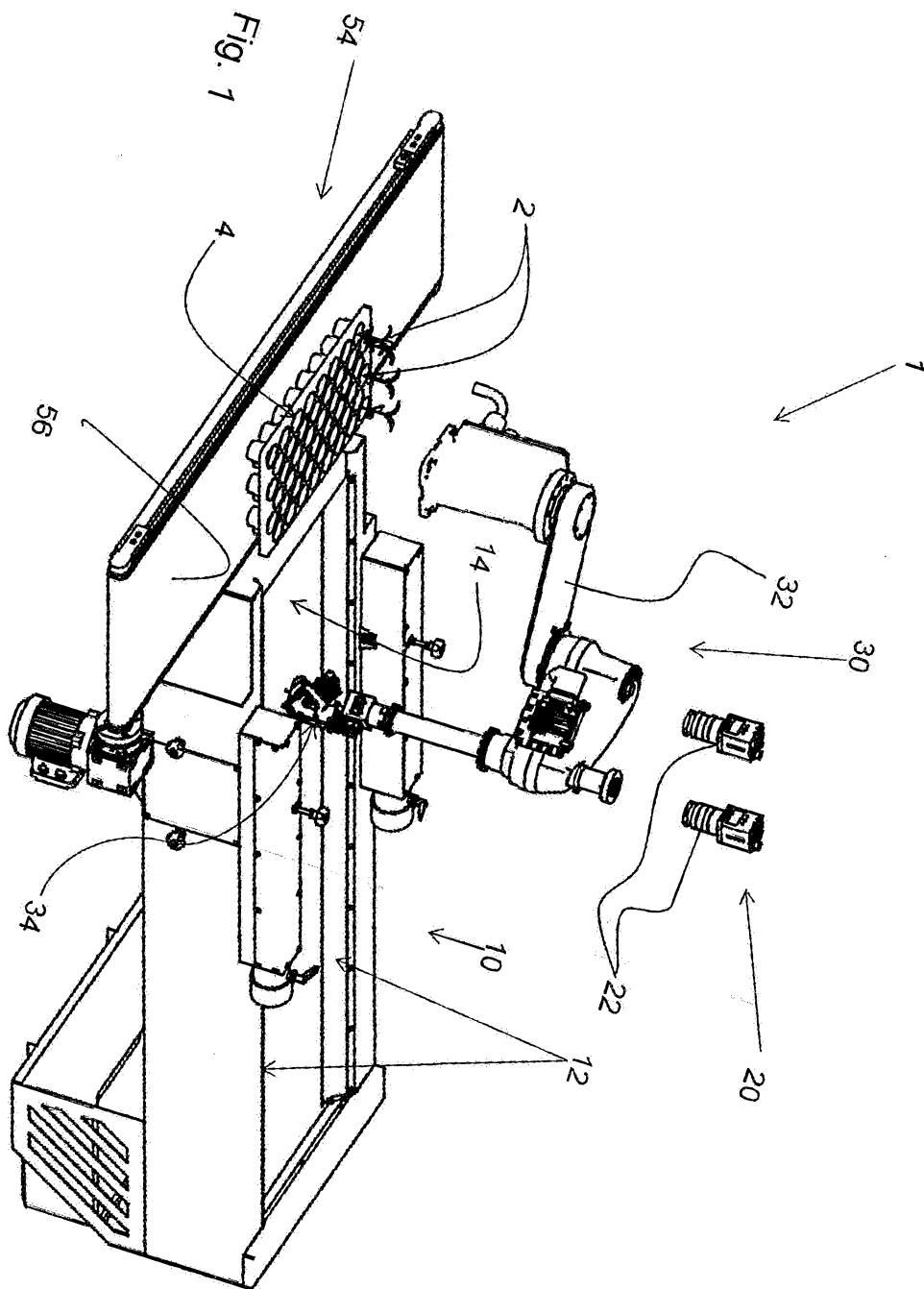
6. Et pluk-og-plant-hoved (34) i henhold til ethvert af kravene 2 til 4, hvori de modstående gribeflader (40) er arrangeret til at blive kilet fra hinanden, når støderen (50) indføres derimellem.
- 5 7. Et pluk-og-plant-hoved (34) i henhold til ethvert af kravene 1 til 7, hvori griberen (36) omfatter mindst ét aflangt element (38a, 38b), og én af de to modstående gribeflader (40) danner en indvendig flade på det aflange element, fortrinsvis hvori griberen omfatter to modstående, aflange elementer, hvor de to modstående gribeflader er tilvejebragt på de modstående aflange elementer; mere fortrinsvis hvori hvert aflange element har en distal ende, hvor en indvendig flade i hver distale ende danner en gribeflade.
- 10
8. Et pluk-og-plant-hoved (34) i henhold til ethvert af kravene 1 til 7, hvori griberen (36) omfatter en knibtang, der har modstående fingre med hovedsageligt plane, distale gribeflader (40).
- 15
9. Et pluk-og-plant-hoved i henhold til krav 8, når afhængig af nogen af kravene 2 til 6, hvori støderen (50) er aflang med en distal ende, den distale ende er kileformet, og støderen er placeret mellem fingrene på knibtangen, hvorved støderen og fingrene kan bevæges i forhold til hinanden til aksial frem- og tilbagegående bevægelse af støderen til indføring mellem de modstående gribeflader (40).
- 20
10. Et pluk-og-plant-hoved (34) i henhold til ethvert af kravene 1 til 9, hvori griberen (36) kan drejes lodret.
- 25
11. Et pluk-og-plant-hoved (34) i henhold til ethvert af kravene 1 til 10, hvori griberen (36) er vinklet fra vandret med fra 10° til 80° , fortrinsvis fra 20° til 70° , og mest fortrinsvis fra 30° til 60° , når griberen er i en opsamlingsretning.

12. Et pluk-og-plant-hoved (34) i henhold til ethvert af kravene 2 til 6 eller 9, eller 10 til 11, når afhængig af krav 2, hvori støderen (50) er hovedsageligt parallel med griberen (36).
- 5 13. Et pluk-og-plant-hoved (34) i henhold til ethvert af kravene 1 til 12, hvori pluk-og-plant-hovedet desuden omfatter et afstandsstykke (46), der er arrangeret til at holde griberen (36) i en afstand fra en vandret stiklingsforsyningsflade (14) under en opsamlingshandling.
- 10 14. En robotarm (32), der omfatter et pluk-og-plant-hoved (34) i henhold til ethvert af kravene 1 til 13.
15. Apparat til placering af stiklinger (2) af planter i et dyrkningsmedium (4), som omfatter:
- 15 a. et stiklingsforsyningssystem (10) til forsyning af en pluralitet af stiklinger, fortrinsvis omfattende en hovedsageligt vandret forsyningsflade (14), hvorpå pluraliteten af stiklinger kan spredes;
- b. et kamerasystem (20) til identificering af stiklinger blandt pluraliteten af stiklinger, der er tilvejebragt af forsyningssystemet, som er egnet til
- 20 individuel opsamling gennem brug af mønstergenkendelse;
- c. en robotarm (32), der er forsynet med et pluk-og-plant-hoved (34), hvori nævnte pluk-og-plant-hoved er i overensstemmelse med ethvert af kravene 1 til 13.
- 25 16. Apparat i henhold til krav 15, hvori pluk-og-plant-hovedet (34) er arrangeret til opsamling af en stikling (2) ved en forudbestemt afstand fra en ende deraf til plantning i dyrkningsmediet (4) afhængigt af indlæsning af ét eller flere billeder fra kamerasystemet (20).

17. Metode til plantning af plantestiklinger (2) i et dyrkningsmedium (4), som omfatter:
- a. tilvejebringelse af en spredt pluralitet af stiklinger på en hovedsageligt vandret forsyningsflade (14) i et stiklingsforsyningssystem (10);
 - 5 b. identificering via mønstergenkendelse mindst én stikling blandt pluraliteten af stiklinger som egnet til individuel opsamling;
 - c. plukning af identificerede stikling fra forsyningsfladen i en hovedsageligt vandret retning, med et pluk-og-plant-hoved (34) på en robotarm (32);
 - 10 d. rotation af den plukkede stikling i en hovedsageligt lodret retning med en planterbar ende af stiklingen vendt fremad, med pluk-og-plant-hovedet; og
 - e. plantning af den hovedsageligt vandrette stikling i et dyrkningsmedium ved hjælp af pluk-og-plant-hovedet;
- hvor
- 15 pluk-og-plant-hovedet er i overensstemmelse med ethvert af kravene 1 til 13.
18. Computerlæsbart medie, der har computerlæsbare instruktioner gemt derpå til udførelse, når det udføres af en processor i et apparat, i henhold til ethvert af kravene 15-16, af metoden, som defineret i krav 17.

DRAWINGS

DK/EP 3247196 T3



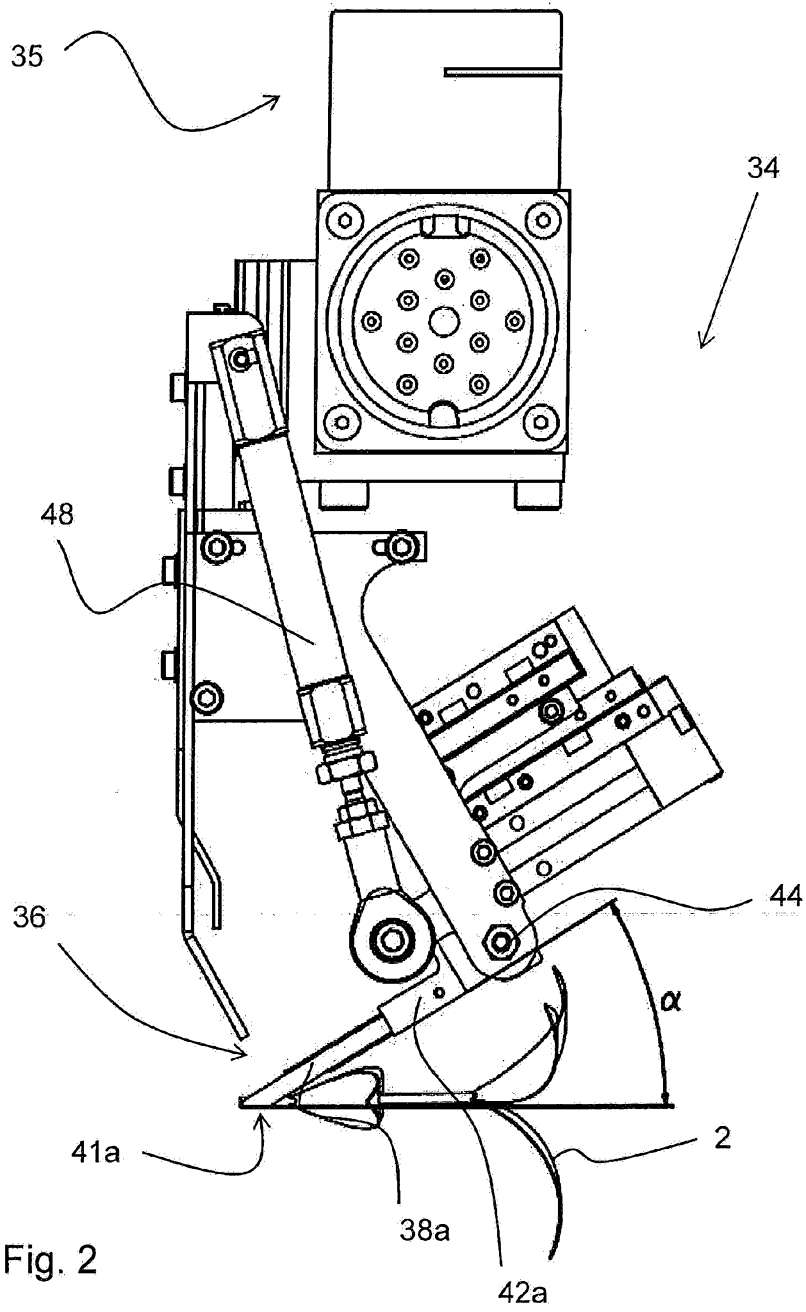


Fig. 2

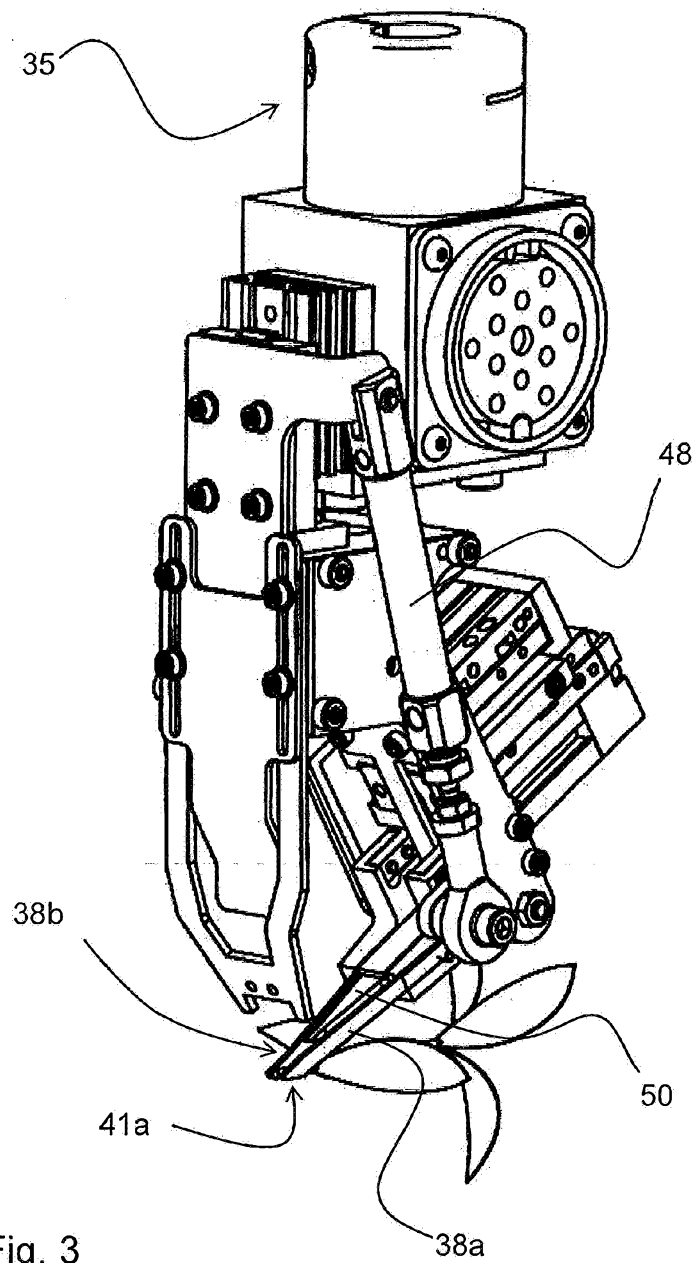


Fig. 3

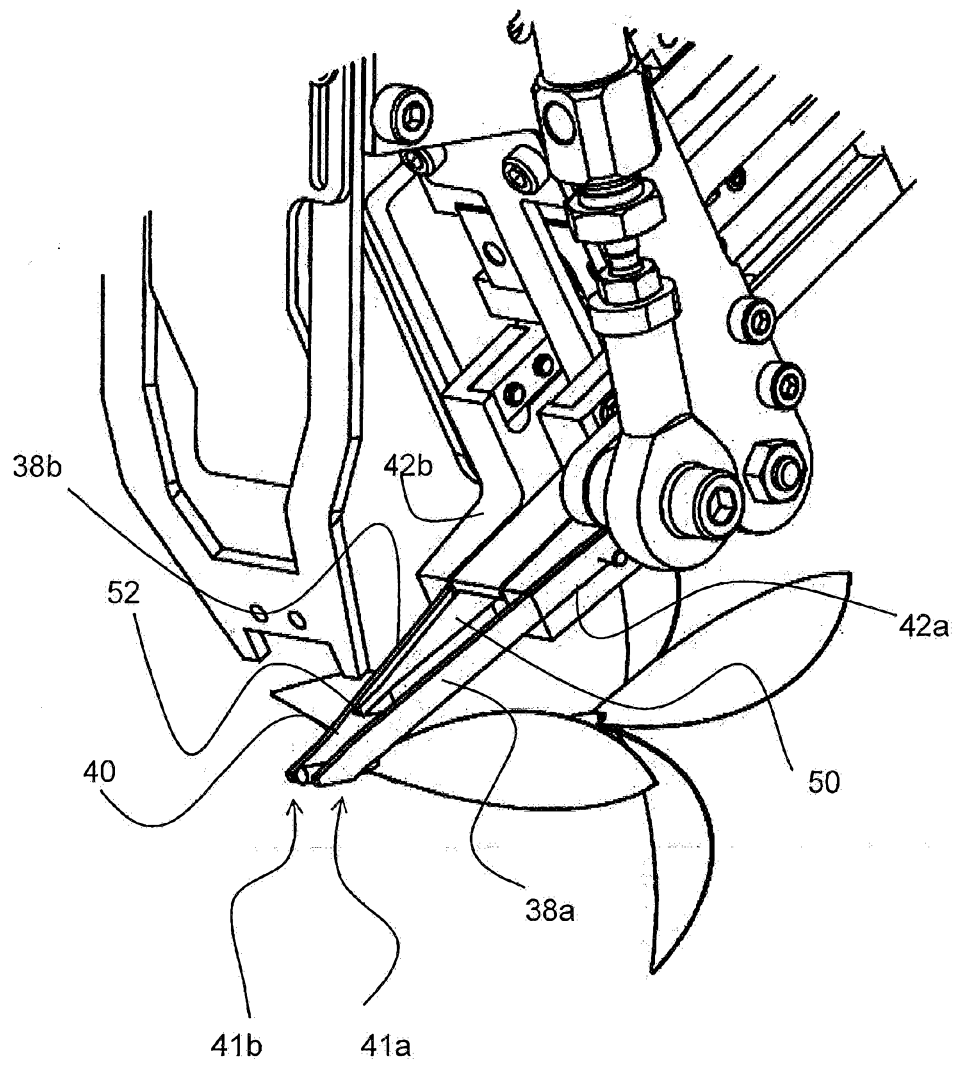
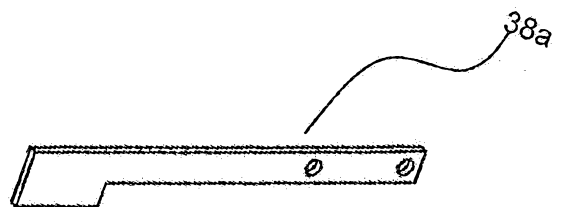
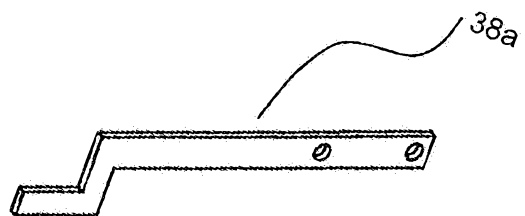
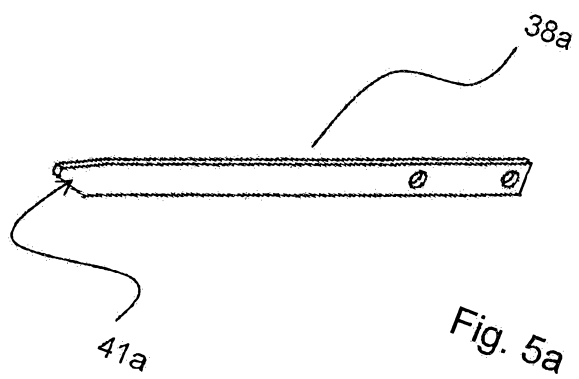


Fig. 4



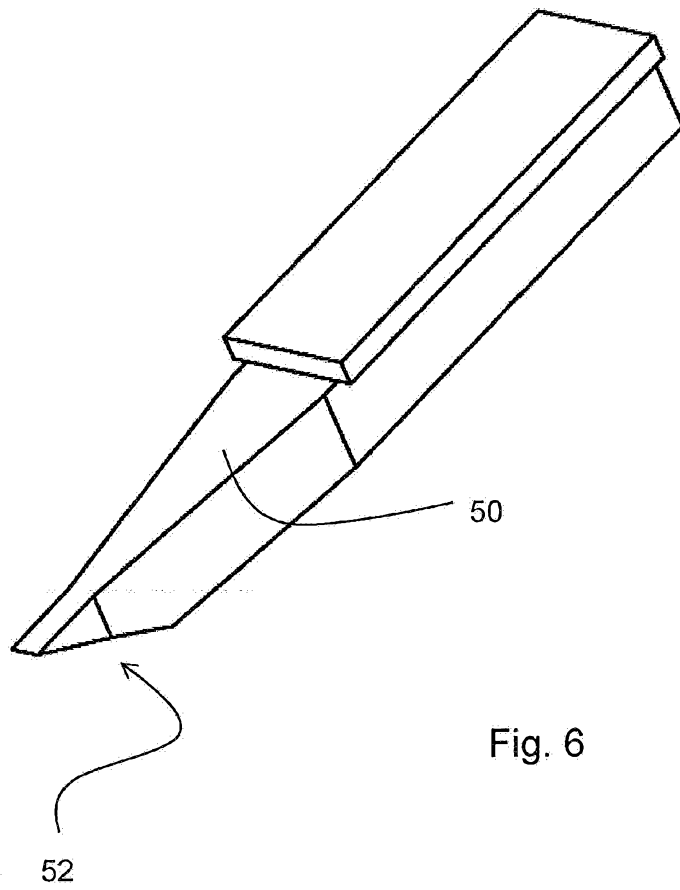


Fig. 6

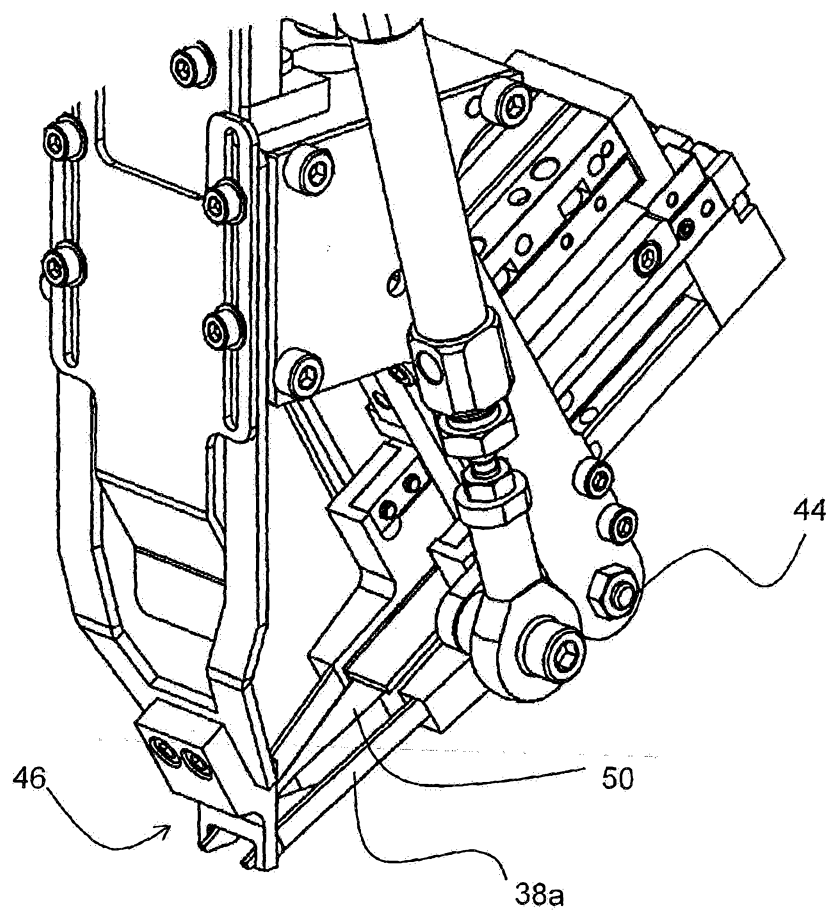


Fig. 7

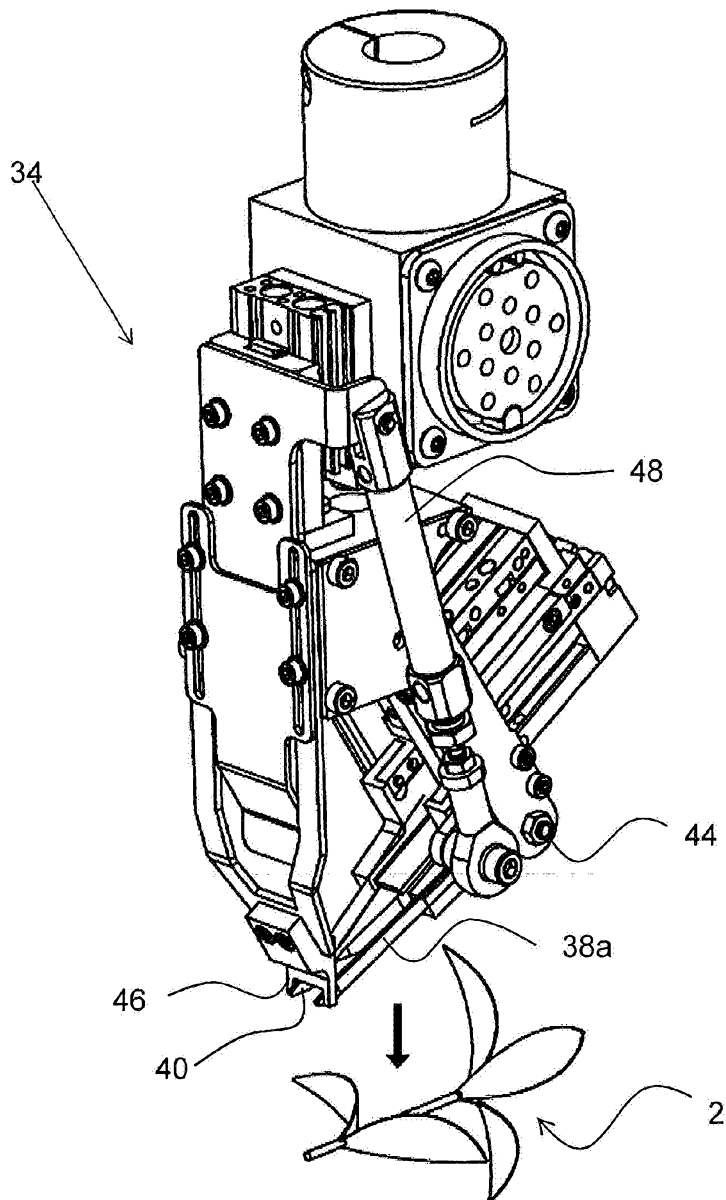
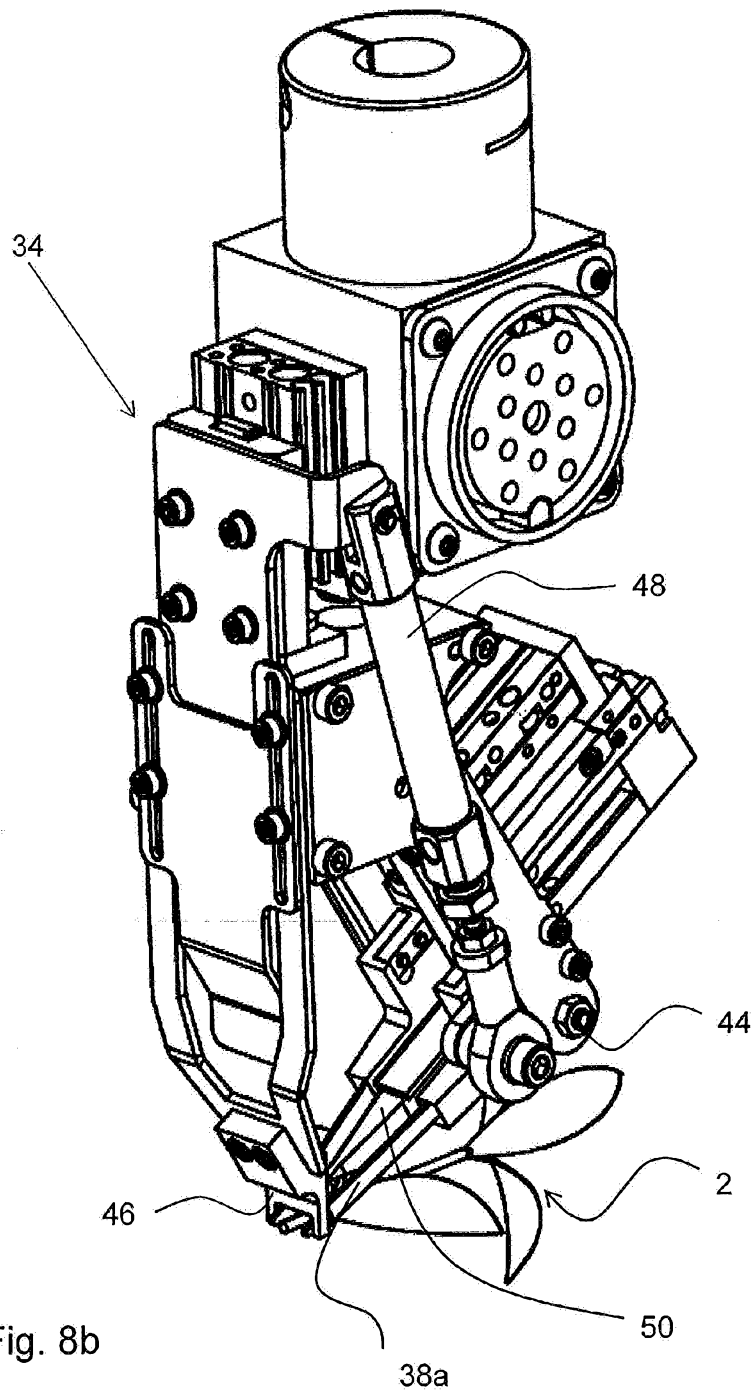


Fig. 8a



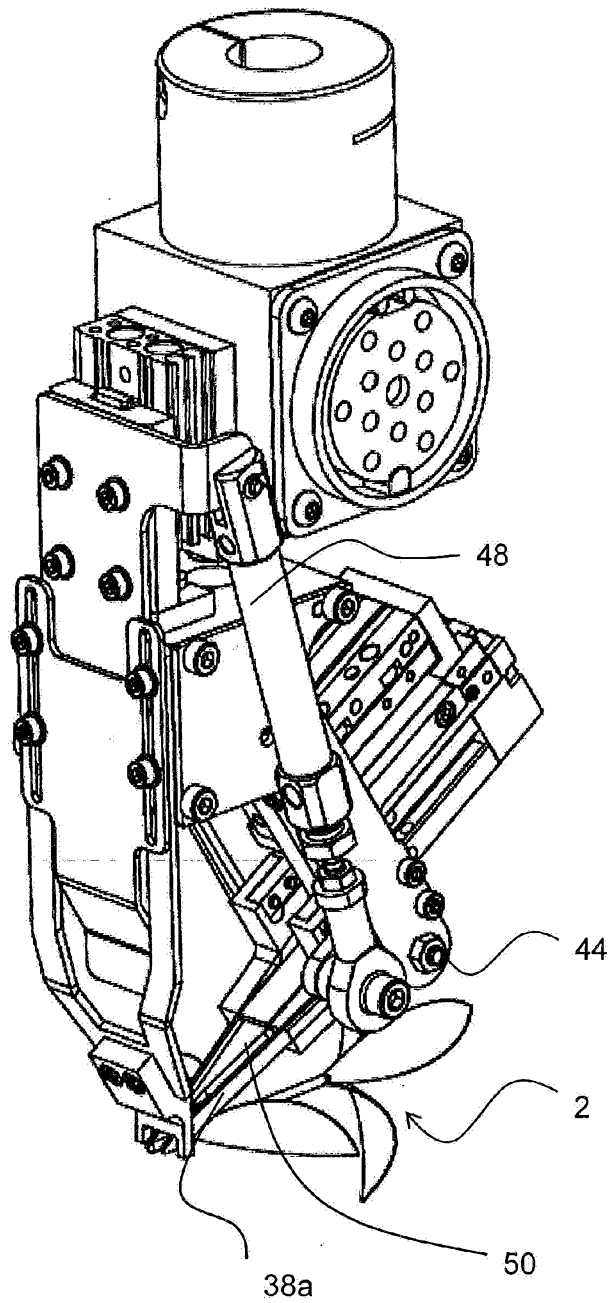


Fig. 8c

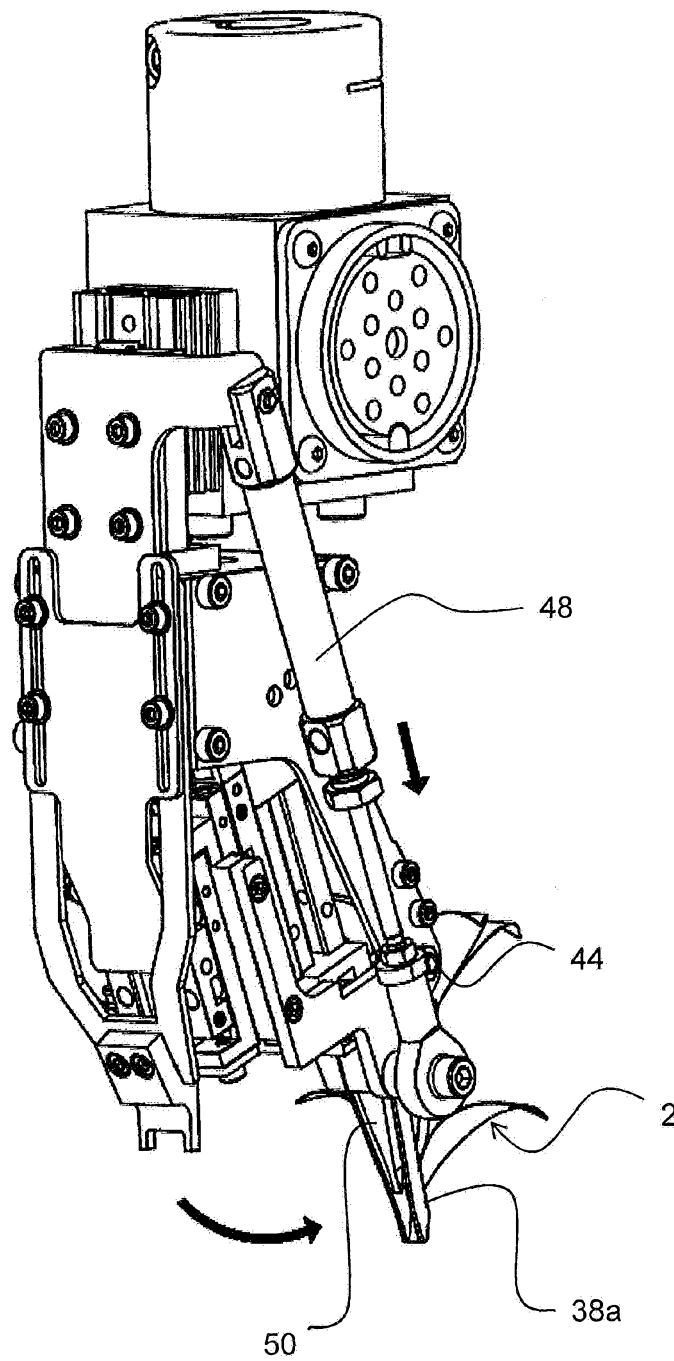


Fig. 8d

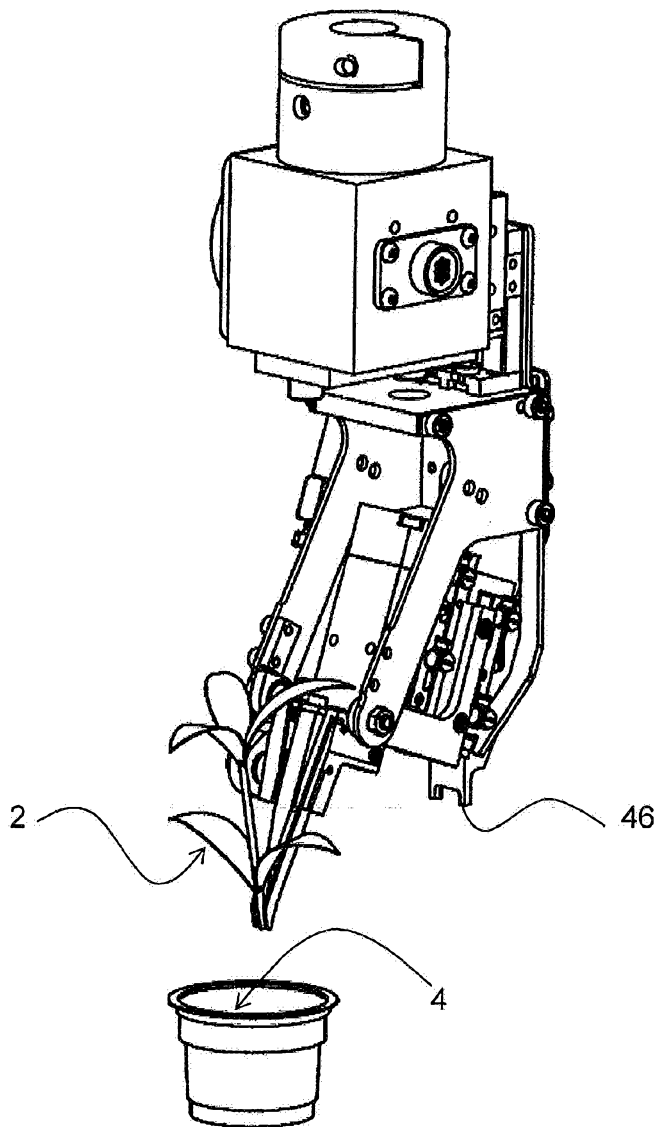


Fig. 8e

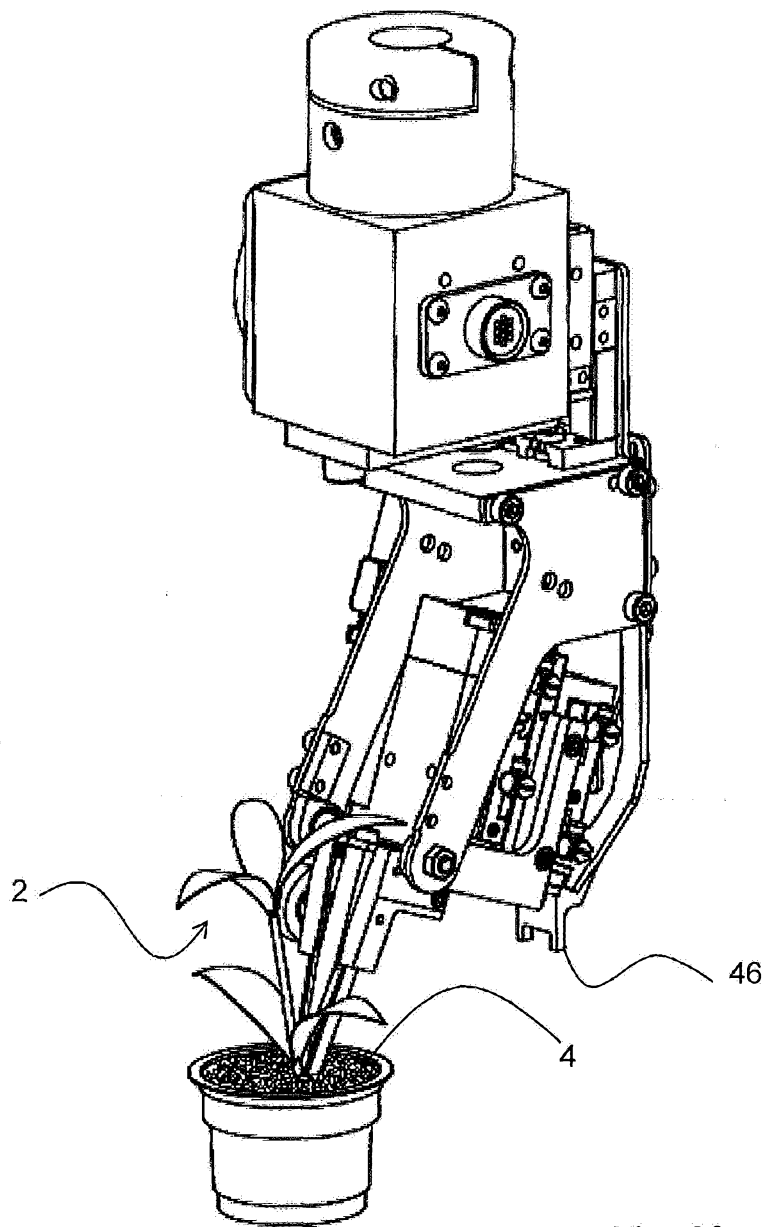


Fig. 8f

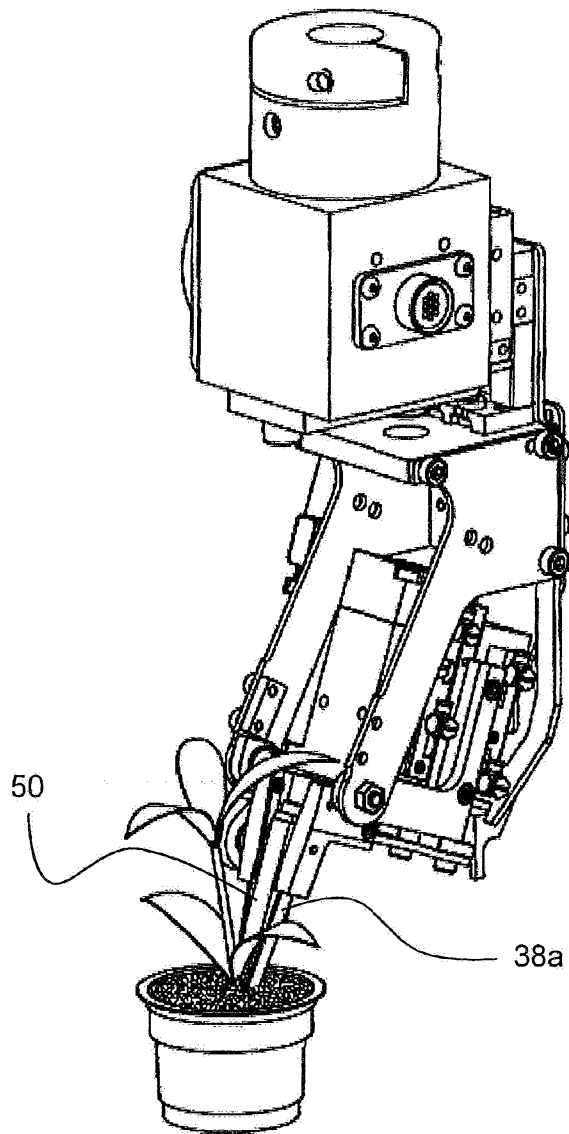


Fig. 8g

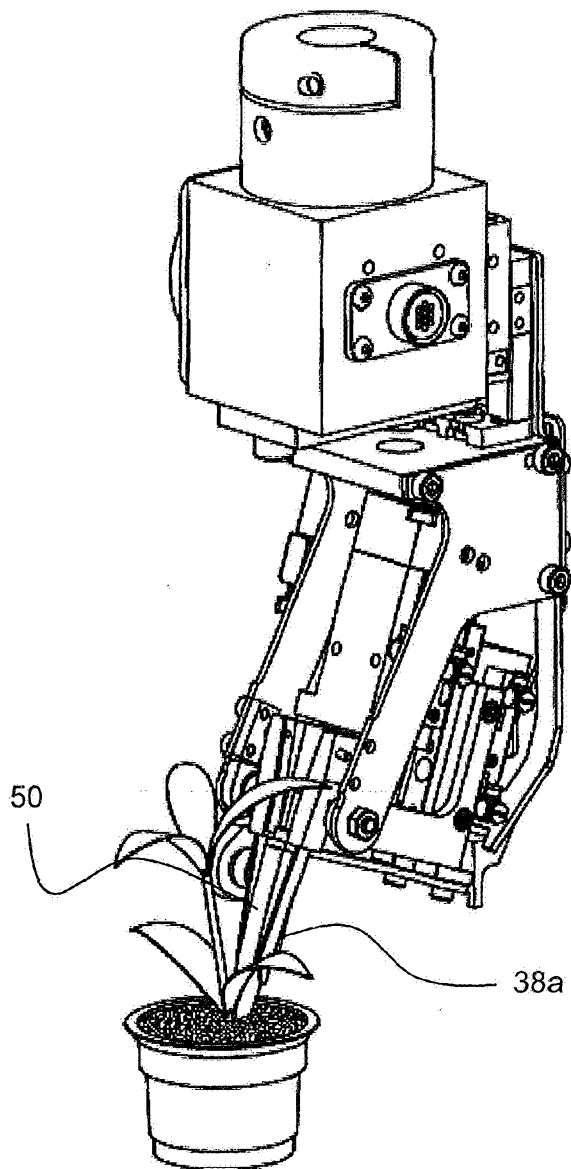


Fig. 8h

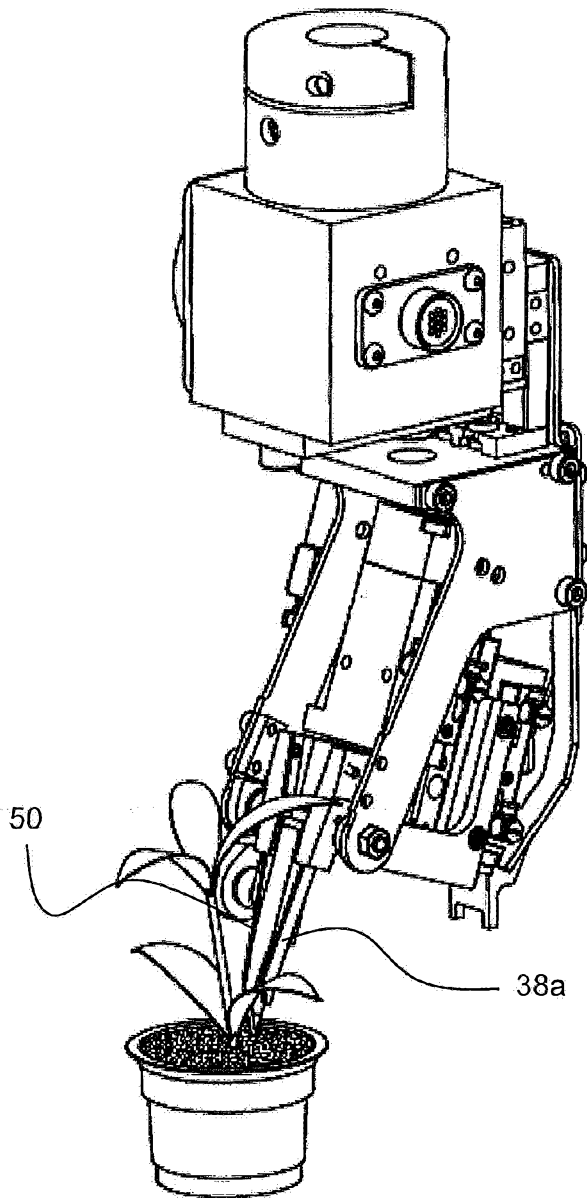


Fig. 8i

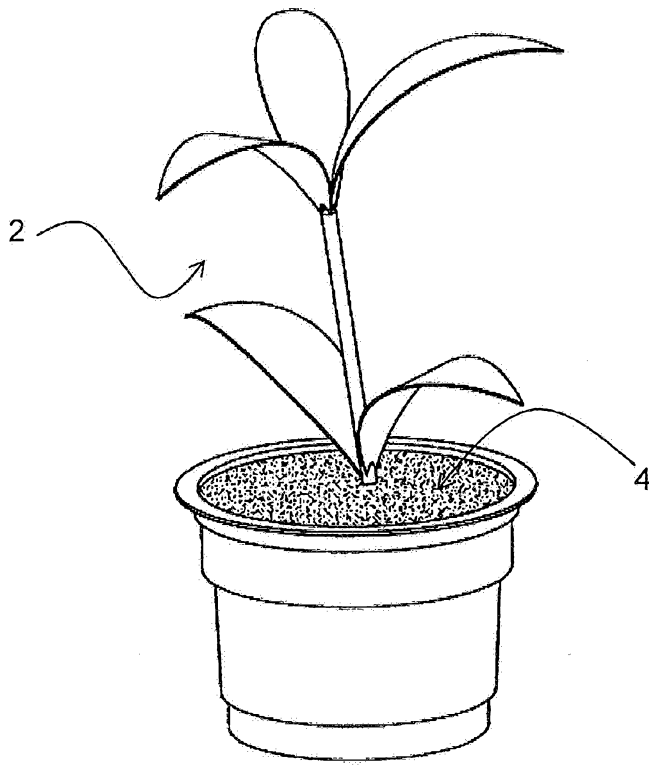


Fig. 8j