

(19) World Intellectual Property Organization
International Bureau



(43) International Publication Date
20 September 2007 (20.09.2007)

PCT

(10) International Publication Number
WO 2007/106874 A2

(51) International Patent Classification:
F16H 37/02 (2006.01)

(21) International Application Number:
PCT/US2007/064010

(22) International Filing Date: 14 March 2007 (14.03.2007)

(25) Filing Language: English

(26) Publication Language: English

(30) Priority Data:
60/782,046 14 March 2006 (14.03.2006) US

(71) Applicant (for all designated States except US): AU-
TOCRAFT INDUSTRIES, INC. [US/US]; 10001 N. W.
2nd, Oklahoma City, OK 73127 (US).

(72) Inventors; and

(75) Inventors/Applicants (for US only): MILES, David,
Michael [US/US]; 22360 N. Cedar Farm Road, Edmond,
OK 73003 (US). PETERS, Todd, Russell [US/US];
12570 Buno Road, Milford, Michigan 48380 (US).

(74) Agent: O' HAGAN, Chistopher, P.; Carstens & Cahoon,
LLP, Po Box 802334, Dallas, TX 75380 (US).

(81) Designated States (unless otherwise indicated, for every
kind of national protection available): AE, AG, AL, AM,
AT, AU, AZ, BA, BB, BG, BR, BW, BY, BZ, CA, CH, CN,
CO, CR, CU, CZ, DE, DK, DM, DZ, EC, EE, EG, ES, FI,
GB, GD, GE, GH, GM, GT, HN, HR, HU, ID, IL, IN, IS,
JP, KE, KG, KM, KN, KP, KR, KZ, LA, LC, LK, LR, LS,
LT, LU, LY, MA, MD, MG, MK, MN, MW, MX, MY, MZ,
NA, NG, NI, NO, NZ, OM, PG, PH, PL, PT, RO, RS, RU,
SC, SD, SE, SG, SK, SL, SM, SV, SY, TJ, TM, TN, TR,
TT, TZ, UA, UG, US, UZ, VC, VN, ZA, ZM, ZW.

(84) Designated States (unless otherwise indicated, for every
kind of regional protection available): ARIPO (BW, GH,
GM, KE, LS, MW, MZ, NA, SD, SL, SZ, TZ, UG, ZM,
ZW), Eurasian (AM, AZ, BY, KG, KZ, MD, RU, TJ, TM),
European (AT, BE, BG, CH, CY, CZ, DE, DK, EE, ES, FI,
FR, GB, GR, HU, IE, IS, IT, LT, LU, LV, MC, MT, NL, PL,
PT, RO, SE, SI, SK, TR), OAPI (BF, BJ, CF, CG, CI, CM,
GA, GN, GQ, GW, ML, MR, NE, SN, TD, TG).

Published:

— without international search report and to be republished
upon receipt of that report

For two-letter codes and other abbreviations, refer to the "Guid-
ance Notes on Codes and Abbreviations" appearing at the begin-
ning of each regular issue of the PCT Gazette.

(54) Title: IMPROVED WHEELCHAIR

(57) Abstract: A system for providing an automated axial force to a continuously variable transmission (CVT) in a wheelchair. An electronic transmission control receives one or more input signals generated by throttle position or other variables. The microproces-
sor generates an output signal that adjusts the axial force applied to a CVT thereby automatically adjusting the input to output ratio. The invention also provides a manually-controlled variator is designed for use on a wheelchair. The manual shifter hydraulically
adjusts an axial force imparted on a variator in communication with a wheelchair wheel and a hand rim. Application of the axial
force causes the hand rim input and wheelchair wheel output ratio to change, permitting a wheelchair operator to manually adjust
the input to output ratio to more easily operate the wheelchair.



WO 2007/106874 A2

IMPROVED WHEELCHAIR

CROSS-REFERENCE TO RELATED APPLICATIONS

This application claims the benefit of and priority to U.S. Provisional Patent Application No. 60/782,046 filed March 14, 2006 the technical disclosures of which are hereby incorporated herein by reference.

TECHNICAL FIELD OF INVENTION

The present invention relates generally to a continuously variable transmission (CVT) and specifically to an improved wheelchair that incorporates a CVT.

BACKGROUND OF THE INVENTION

A transmission is any mechanical linkage that converts an input torque to an output torque. It usually involves a series of gears that have differing diameters, allowing a first gear at a first rotation rate to link to a second gear rotating at a second rate. The most common application for transmissions is in a vehicle. For example, a car may have an automatic transmission or a manual transmission. A bicycle has a simple transmission that links the pedals to the hub of the rear wheel.

Transmissions allow an input force to be converted into a more useful and appropriate output. However, by using gears and linkages, a typical transmission may only have four or five ratios available. For example, a four speed automatic transmission in a car has only four sets of output gears to couple to the engine's input. A ten speed bike has only ten ratios of input to output. A need exists for a transmission that is not limited by the number of gears. Yet, to place a larger number of gears into a transmission increases its costs and weight and space requirements.

A continuously variable transmission (CVT) or continuously variable planetary (CVP) is a transmission that eliminates the need for a specified number of gears. Instead it allows an almost limitless number of input to output ratios. This is a benefit because it allows an output to be achieved, i.e. the speed of a vehicle, at an optimal input, i.e. the rpm of the engine. For example, an engine might be most efficient at 1800 rpm. In other words, the peak torque output for the engine might be

achieved at this engine rpm, or perhaps the highest fuel economy. Consequently, it may be desirable to run at a specified RPM for an economy mode or a power mode. Yet, in third gear, the car might be going faster at 1800 rpm than the driver desires. A continuously variable transmission would allow an intermediate ratio to be achieved that allowed the optimal input to achieve the desired output.

CVTs have a variator for continuously variable adjustment of the ratio. A customary structure is a belt drive variator having two pairs of beveled pulleys and rotating a torque-transmitter element therein, such as a pushing linked band or a chain. The beveled pulleys are loaded with pressure from the transmission oil pump in order, on one hand, to actuate the ratio adjustment and, on the other, to ensure a contact pressure needed for transmission of the torque upon the belt drive element. Another usual structure is a swash plate variator in semi-toroidal or fully toroidal design.

Examples of CVTs are exemplified by U.S. Pat. Nos. 6,419,608 and 7,011,600 assigned to Fallbrook Technologies of San Diego, California. In each of those references the axial movement of a rod or an axial force as indicated by numeral **11** of each reference is used to vary the input to output ratio of such transmissions. While a continuously variable transmission is artful on paper, the realities of making one work smoothly requires significant know how. Consequently, a need exists for a system that permits axial shifting of the rod **11**.

While CVTs have primarily been applied to more conventional vehicles such as motor scooters and bicycles, wheelchairs represent another class of transport that has been inadequately equipped over the years.

SUMMARY OF THE INVENTION

In one aspect, the present invention is directed towards a system for providing an automated axial force to a CVT. In one embodiment, the system comprises an electronic transmission control for a CVT that is adjusted by an axial force provided by a motor. The electronic transmission controls comprises a sensor for receiving an input signal that is dependent upon one or more automatically-generated variables such as throttle position, the current draw from the battery, the variator setting, the level of charge in the battery or battery level, the control settings of the motor controller (e.g., linear or s-curve), the wind direction, the wind speed, and the tire pressure. A microprocessor processes the input signals and transmits an output signal to a motor that adjusts an axial force that is applied to a variator. The axial force can be applied by a translational force, or a threaded screw. In another embodiment, the transmission ratio is set using a push button control.

The present invention also provides an improved wheelchair having a manually controlled CVT. In one embodiment, the manual control comprises a piston bounded by a first fluid reservoir and second fluid reservoir coupled to a hydraulically actuated piston having a pushing fluid reservoir and a pulling fluid reservoir. Application of downward force to the piston causes fluid to exit from the second fluid reservoir and causes fluid to enter the pulling fluid reservoir. Simultaneously, fluid is pulled into the first fluid reservoir and out of the pushing fluid reservoir. Consequently, the hydraulically actuated piston moves in a first axial direction away from the manually-controlled variator.

Alternatively, application of upward force to the piston causes fluid to exit from the first fluid reservoir and causes fluid to enter the pushing fluid reservoir. Simultaneously, fluid is pulled into the second fluid reservoir and out of the pulling fluid reservoir. Consequently, the hydraulically actuated piston moves in a second axial direction towards the transmission.

The invention permits a user to adjust the input to output ratio based upon conditions including the slope of the navigational path or the speed of a wheelchair. Hence, this invention provides a manually-controlled variator for a wheelchair that a person can use to easily adjust the input to output ratio. Consequently, the instant invention provides an easy way to use a continuously variable transmission or manually-controlled variator on a wheelchair.

In one aspect, the present invention permits one to manually adjust the input to output ratio applied to two or more wheels and thereby steer the vehicle.

The above as well as additional features and advantages of the present invention will become apparent in the following written detailed description.

BRIEF DESCRIPTION OF THE DRAWINGS

The novel features believed characteristic of the invention are set forth in the appended claims. The invention itself, however, as well as a preferred mode of use, further objectives and advantages thereof, will best be understood by reference to the following detailed description of an illustrative embodiment when read in conjunction with the accompanying drawings, wherein:

Figure 1 is a schematic representation depicting the operation of manually controlled variator in a light electric vehicle;

Figure 2 is a schematic representation depicting various potential embodiments of the present invention in a light electric vehicle;

Figure 3A is a schematic representation of the automatic operation theory in accordance with one embodiment of the present invention;

Figure 3B is a schematic representation of the 90° gearbox in accordance with one embodiment of the present invention;

Figure 4A is a schematic representation of a linear actuator in accordance with an alternative embodiment of the present invention;

Figure 4B is a schematic representation of a servo motor mounted on a rear wheel in accordance with an alternate embodiment of the present invention;

Figure 4C is a schematic representation of an alternate servo motor design in accordance with another embodiment of the present invention;

Figure 4D is a simplified schematic representation of a servo motor mounted remote from the rear wheel in accordance with an alternative embodiment of the present invention;

Figures 5 is a side view illustration of a manually controlled variator mounted on a wheelchair in accordance with one embodiment of the present invention;

Figure 6 is a rear view illustration of the manually-controlled variator and wheelchair depicted in **Figure 5**;

Figure 7 is a perspective view illustration of the manually-controlled variator and wheelchair depicted in **Figure 5**;

Figure 8 is a schematic representation of the input rpm and resultant output rpm based upon the lever position in accordance with one embodiment of the present invention;

Figure 9 is a simplified schematic representation depicting a configuration that permits manual steering of a vehicle having two sets of three variators with each set in series in accordance with one embodiment of the present invention; and

Figure 10 is a partial simplified schematic representation depicting two variators in series in accordance with one embodiment of the present invention.

DETAILED DESCRIPTION

Figure 1 is a schematic representation depicting the operation of manually controlled CVT or variator in a light electric vehicle, such as an motorized wheelchair. As shown in **Figure 1**, a manual push button control box **101** has buttons corresponding to a signal output **108** of 0% **102**, 25% **103**, 50% **104**, 75% **105**, and 100% **106** sent to a microprocessor **112**. The microprocessor output can be shown on a display **150**. The microprocessor **112** interfaces with a motor control board **114** which receives power from a battery pack **118**.

A servo motor **120** engages a 90° gearbox **122** which provides an axial force **130** to a variator (CVT) **132** in contact with the rear wheel **134**. As used herein, the term “variator” is synonymous with a continuously variable transmission or an infinitely variable transmission, or a continuously variable planetary, terms known to those skilled in the art. For example, CVTs can include devices where power transfer occurs through an endless torque-transmitting means that circulates between two pairs of conical disks whereby the effective radius of each conical disk pair is variable by changing the spacing between the disks. Other steplessly adjustable transmissions can be based upon rolling elements that run frictionally engaged between suitable toroidal surfaces.

The rear wheel **134** is powered by a chain **136** or other equivalent means connected to a drive motor **140** (e.g., Briggs & Stratton ETEK). The motor **140** speed is regulated by a current sent by a motor control device **144**. The motor control device **144** is regulated by a throttle **146** and is powered by a battery **118**.

While a user of the electric vehicle can manually shift gears via the push button control box **101**, it is also desirable to have an automatic shifting transmission to permit an electric wheelchair to operate in a power mode or an economy mode.

Figure 2 is a schematic representation depicting various potential embodiments of the present invention in a light electric vehicle. **Figure 3A** is a simplified schematic representation of the automatic operation theory in accordance with one embodiment of the present invention. Rather than using a push button control box **101** to manually control the transmission ratio as shown in **Figure 1**, one or more automatically-generated variables are used to automatically adjust the CVT. For example, referring to **Figure 2** and **Figure 3A**, the amount of current being drawn from the motor control device **144** as measured by a current sensor **242** comprises an

automatically generated variable that can be used as an input signal **244** to the microprocessor **112**.

Motor controllers such as those available from Altrax of Grants Pass, OR can be used. In one embodiment, the microprocessor **112** comprises a basic stamp board available from Parallax, Inc. of Rocklin, CA. The microprocessor **112** can be programmed to generate a lookup table to provide optimum set points for variable inputs to obtain either the best performance or optimal efficiency of the wheelchair.

Referring to **Figure 2** and **Figure 3A**, the wheelchair speed is automatically generated by a sensor **236** mounted on the front wheel **136**. In one embodiment, the sensor **236** comprises a plurality of magnets mounted around the front wheel rim and a hall effect sensor mounted via a bracket and wired to the microprocessor **112**. The hall effect sensor **236** transmits a pulse of input signal to the microprocessor **112** each time a magnet passes the hall effect sensor **236**. Based on the frequency of pulses or input signals the microprocessor **112** can calculate a speed and an output signal to adjust the axial force provided to the CVT.

Similarly, motor speed may also be calculated by placing another hall effect sensor **232** on the motor **140** which provides an input signal **234** to the microprocessor **112** each time a magnet passes the hall effect sensor **232**.

The speed is just one example of an automatically generated variable. Other examples of automatically generated variables include, but are not limited to the throttle position, the current draw from the battery, the variator setting, the level of charge in the battery or battery level, the control settings of the motor control device (e.g., linear or s-curve), and tire pressure.

In the example depicted in **Figure 3A**, the microprocessor **112** receives data from the front wheel speed sensor **236** and current draw sensor **244**. The microprocessor **112** then outputs a signal to the servo **120**, which in turn provides an axial force to the variator **332** to shift in an optimal manner that minimizes current draw **244** or power drain so as to provide optimal efficiency.

Figure 3B is a schematic representation of the 90° gearbox in accordance with one embodiment of the present invention. The gearbox **322** comprises a servo **320** mounted with bolts **310** to the wheelchair frame (not shown). A coupler **323** is disposed between a threaded (worm) shaft **324** and the servo **320**. Upon rotation of the threaded shaft **324**, the wheel **326** rotates as depicted by numeral **328**, causing the

shift shaft **330** to rotate. Such rotation of the shift shaft **330** is converted into an axial force.

The 90° gearbox setup is used to provide a mechanical advantage (i.e. 36:1) and to reduce the size of the protrusion from the side of the wheelchair.

When the system is turned on the servo motor **320** is driven towards home until the shift shaft **330** contacts the home sensor **250** (shown in **Figure 2**). The servo is stopped and the microprocessor **112** sets the internal electronic home position, registering voltage, turns, and rotation direction. In response to button push, based on the last known servo position a comparison is made between the current position and the “button called” position. The microprocessor **112** then drives the servo **320** to the “called” position.

Figure 4A is a simplified schematic representation of a linear actuator in accordance with an alternative embodiment of the present invention. This embodiment uses a rack and pinion setup and can be mounted close inside the frame of the wheelchair. The end **416** of the threaded shaft **424** is adapted to couple between a first tooth-like member **412** and a second tooth-like member **414**. As the servo motor rotates the shaft end **416**, the first tooth-like member **412** is driven axially and thereby provides an axial force to a member **410** that is in communication with the tooth-like member **412** and a variator (not shown).

Figure 4B is a schematic representation of a servo motor mounted on a rear wheel in accordance with an alternate embodiment of the present invention. The servo motor **420** is connected to a shaft **430** having a threaded portion **424** adapted to couple with a threaded variator shaft (not shown). The internal threaded portion **424** allows space for the variator shaft to be pulled in and out. The servo motor **420** turns the shaft **430** thereby causing the threaded portion **424** to move the variator shaft in or out, thus adjusting the variator.

Figure 4C is a schematic representation of an alternate servo motor design in accordance with another embodiment of the present invention. Like the embodiment depicted in **Figure 4B**, the servo motor **420** in this embodiment is also mounted at the rear wheel of the wheelchair. However, in this embodiment, the servo motor **420** is connected to a shaft **430** having a splined portion **425** adapted to couple with a variator shaft (not shown). The servo motor **420** turns the splined shaft **430**, thereby creating an axial force on the variator shaft, thus adjusting the variator.

Figure 4D is a schematic representation of the servo motor in communication with a hub that contains the variator in accordance with another alternate embodiment of the present invention. In this embodiment, a hub **1102** containing the variator is mounted at the rear wheel of the wheelchair (not shown), and the servo motor is mounted up on the wheelchair frame. The rear hub **1102** includes a housing having an axial force that encloses and protects a pulley system coupled to cables **1012** and **1014**. These cables **1012**, **1014** in turn are connected to the servo motor **420**, which alternately pulls cable **1012** or cable **1014** in order to adjust the variator inside the hub **1102**.

While the above description covers examples of how an electronic transmission control can automatically adjust the axial force provided to a variator, the axial force can also be adjusted manually in a motorized or non-motorized vehicle. For example, in accordance with one embodiment of the present invention, a wheelchair is equipped with a manually activated wheel piston assembly that allows a person with a level of disability to exert a constant force to an input and achieve an optimum output to the drive wheels.

Figure 5 is a side view illustration of a manually-controlled variator mounted on a wheelchair in accordance with one embodiment of the present invention. **Figure 6** is a rear view illustration of the manually-controlled variator and wheelchair depicted in **Figure 5**. **Figure 7** is a perspective view illustration of the manually-controlled variator and wheelchair depicted in **Figure 5**.

Referring to **Figures 5, 6, and 7**, in one embodiment the manually-controlled variator comprises a lever **510** having one end pivotally **511** attached **512** to an arm **514** in communication with two pistons **516a 516b**. Each piston **516a 516b** is bound by a first fluid reservoir **518a 518b** and second fluid reservoir **520a 520b**. The first fluid reservoir **518a 518b** is in hydraulic communication with a wheel piston assembly **550a 550b** in axial communication with a CVT **100a 100b**.

Pushing forward on the lever **510** forces the arm **514** downward and forces each piston **516a 516b** downward. As a result, positive hydraulic pressure is applied to the fluid in the reservoir **520a 520b** forcing fluid through the flexible hoses **526a 526b** into a coupler **530** and through hard piping **532a 532b** into a reservoir **552a 552b**. The coupler **530** merely provides a means for switching from a flexible hose **522a 522b 526a 526b** into a rigid line **532a 532b 536a 536b**. This embodiment can be advantageous as it can keep flexible hoses **522a 522b 526a 526b** from interfering

with or becoming tangled with a user's hands, the wheelchair wheel **570a 570b** and/or the hand rim **560a 560b** during rotation.

When positive hydraulic pressure is applied to the pushing reservoir **552a 552b**, the piston **556a 556b** forces the arm **558a 558b** attached to the piston to move in the direction towards the CVT **100a 100b** as indicated by arrow **555a 555b**. Similarly, when positive hydraulic pressure is applied to the pulling reservoir **554a 554b**, the piston **556a 556b** forces the arm **558a 558b** attached to the piston to move in the direction away from the CVT **100a 100b** as indicated by arrow **551a 551b**.

One advantage of the embodiment described above is the efficient design of the hydraulic system. For example, when the lever **510** is pushed forward the arm causes the piston **516a 516b** to push fluid out of the second fluid reservoir **520a 520b** to the pulling reservoir **554a 554b** and simultaneously pull fluid into the first fluid reservoir **518a 518b** from the pulling reservoir **552a 552b**. Consequently, both the first fluid reservoir and second fluid reservoir are in hydraulic communication with the arm **558a 558b** via the piston **556a 556b**. It should be noted that the above example is provided merely for purposes of illustration. For example, in one embodiment, the second fluid reservoir **520a 520b** is not in communication with the second piston **556a 556b**.

Figure 8 is a schematic representation of the Input RPM and resultant Output RPM based upon the variator position in accordance with one embodiment of the present invention. Referring to **Figures 5 and 8** the position of the lever **510** can move from a position closest to the user ("0" position) to a position furthest from the user ("100" position). The present invention permits an operator to easily change the input to output ratio by merely moving the lever **510**.

As used herein, an input to output ratio is defined as the number of hand rim **560a 560b** revolutions divided by the number of corresponding wheelchair wheel **570a 570b** revolutions. For example, referring to **Figure 8**, when the lever is in a position close to zero, one RPM input to the hand rim **560a 560b** results in a greater RPM output by the wheelchair drive wheels **570a 570b**. This is similar to "high gear" in a geared transmission and permits an operator better control to slow downhill movement or rapid level surface movement.

At the intersection of the Input RPM and Output RPM lines, one RPM input to the hand rim equals one RPM at the wheelchair drive wheels **570a 570b**. Such configuration may be desirable for level surface operation. In one embodiment, the

input to output ratio for level surface operations comprises between about 1.0 and about 1.8.

When the lever position is in a position close to 100, an input of one RPM to the hand rims **560a 560b** will equal less than one RPM of input to the wheelchair drive wheels **570a 570b**. Such configuration is similar to low gear in a geared transmission and permits an operator to more easily climb inclined surfaces. In one embodiment, the input to output ratio for climbing an inclined surface comprises between about 0.5 and about 1.0.

Figure 9 is a simplified schematic representation depicting a configuration that permits manual steering of a vehicle having two sets of three variators with each set in series in accordance with one embodiment of the present invention. As shown in **Figure 9**, each variator **900a 900b 900c 900d 900e 900f** has a corresponding wheel piston assembly **950a 950b 950c 950d 950e 950f**. The wheel piston assemblies are similar in operation to the assembly depicted in **Figure 7**.

In this embodiment, steering is achieved by changing the input to output ratio to a first set of variators **900a 900b 900c** in communication with drive wheels **970a 970b 970c** on a first side of a vehicle relative to a second set of variators **900d 900e 900f** in communication with wheels **970d 970e 970f** on a second side of a vehicle. For example, pushing forward on the first lever **910a** forces the piston **916a** downward. As a result, positive hydraulic pressure is applied to the fluid in the reservoir **920a** forcing fluid through the flexible hose **926a** into a coupler **930a** and through hard piping **932a** into a reservoir **952a**. When positive hydraulic pressure is applied to the pushing reservoir **952a**, the piston **956a** forces the arm **958a** attached to the piston to move in the direction towards the variator **100** as indicated by arrow **955a**.

Similarly, by pulling back on the first lever **910a** positive hydraulic pressure is applied to the first fluid reservoir **918a** through the flexible hose **922a** and through the hard piping **936a** to the pulling reservoir **954a**. Consequently, the piston **956a** forces the arm **958a** attached to the piston to move in the direction away from the CVT **900a** as indicated by arrow **951a**.

In one embodiment, one or more of the variators **900a 900b 900c 900d 900e 900f** comprise an infinitely variable transmission (IVT). Consequently, adjusting the axial direction applied to the first set of variators **900a 900b 900c** can turn the first set of wheels **970a 970b 970c** in a direction different from the second set of wheels **970d**

970e 970f. As a result, the vehicle can have a little or no turning radius. Further, such embodiment can be used to manually put the vehicle in reverse.

As previously discussed, a variator is designed to vary an input to output ratio in the same way as gears change the input to output ratio on a car or bicycle. The input to output ratio is changed based upon the axial movement of a rod connected to the variator. The axial movement can be provided by a manual hydraulic system as exemplified by **Figure 7**, by a manual electric system as exemplified by **Figure 1**, or by a manual mechanical system as described by co-pending application U.S. serial number 11/409,846. Furthermore, the axial movement, and hence input-to-output ratio, can also be adjusted automatically based upon an automatically generated input signal. The axial adjustment can occur through hydraulic, electrical, or mechanical means.

The present invention also contemplates the combination of the various ways of changing the input to output ratio. One example of the way in which the variators can be combined is depicted in **Figure 10**, which is a partial simplified schematic representation depicting two variators in series in accordance with one embodiment of the present invention.

As shown in **Figure 10**, an input RPM is provided by a rotating member **1140** attached to a motor (not shown). The rotating member **1140** can create rotation in input shaft **1132a** connected to a first variator **1000a** by a chain, cable **1135a** or other endless torque-transmitting means. The first variator output shaft is connected to a rotating member **1034a** connected to a second variator **1000b** input shaft **1132b**.

The first variator input-to-output ratio can be adjusted by axial movement of a rod **1110a** that can be adjusted by hydraulic, electrical, or mechanical device. The second variator **1000b** output shaft is connected to a wheel **1070**. Consequently, a wider range of input-to-output ratios can be achieved by having two or more variators in series. For example, if the first variator is capable of achieving an input to output ratio of 1:10 and the second variator is capable of achieving an input to output ratio of 1:10, an overall input to output ratio of 1:100 can be achieved. Furthermore, a wider range of control can be achieved. For example, in one embodiment, a second device for adjusting a second axial force **1111b** to a second continuously variable transmission or variator **1000b** is based upon an automatically generated output signal such as vehicle speed. Such embodiment can be beneficial to provide an overdrive or ultra-low gear for climbing a hill.

The description of the present invention has been presented for purposes of illustration and description, and is not intended to be exhaustive or limited to the invention in the form disclosed. Many modifications and variations will be apparent to those of ordinary skill in the art. The embodiment was chosen and described in order to best explain the principles of the invention, the practical application, and to enable others of ordinary skill in the art to understand the invention for various embodiments with various modifications as are suited to the particular use contemplated.

CLAIMS:

We claim:

1. A wheelchair, comprising:
 - (a) a battery-powered motor in mechanical communication with the rear drive wheels of the wheelchair;
 - (b) at least two continuously variable transmissions (CVTs) mounted to the rear drive wheels, wherein the CVTs adjust the RPM ratio between the motor and the drive wheels;
 - (c) a microprocessor;
 - (d) a servo motor in mechanical communication with the CVT, wherein the servo motor provides an axial force to adjust the CVT; and
 - (e) an input means for providing data to said microprocessor, wherein the microprocessor instructs the servo motor to adjust the transmission ratio of the CVTs according to the data provided by the input means.
2. The wheelchair according to claim 1, wherein the input means comprises a manual push button control.
3. The wheelchair according to claim 1, wherein the input means comprises a plurality of sensors that provide said microprocessor with data about the operating status of the wheelchair, wherein the microprocessor uses lookup tables of optimum set points for vehicle data to automatically instruct the servo motor to adjust the CVT.
4. The wheelchair according to claim 3, wherein the wheelchair data provided to the microprocessor by said sensors comprises at least one of the following:
 - (a) wheelchair speed;
 - (b) motor speed;
 - (c) throttle position;
 - (d) current draw from a battery;
 - (e) battery level;
 - (f) CVT setting;
 - (g) control settings of a motor control device; and
 - (h) tire pressure.

5. The wheelchair according to claim 1, further comprising a 90° gearbox that provides mechanical communication between the servo motor and the CVTs.
6. The wheelchair according to claim 1, further comprising a rack and pinion style linear actuator that provides mechanical communication between the servo motor and the CVTs.
7. The wheelchair according to claim 1, further comprising a second servo motor, wherein the servo motors are mounted on the rear wheels, adjacent to the CVTs.
8. The wheelchair according to claim 1, further comprising a pulley system and cables that provide mechanical communication between the servo motor and the CVTs.
9. A wheelchair, comprising:
 - (a) at least two continuously variable transmissions (CVTs) mounted to the rear drive wheels, wherein the CVTs adjust the RPM ratio between the drive wheels and hand rims mounted on the drive wheels;
 - (b) at least one manual lever for adjusting the transmission ratio of the CVTs;
 - (c) at least one hydraulic system that provides communication between said manual lever and the CVTs.
10. The wheelchair according to claim 9, further comprising separate manual levers and hydraulic systems for each rear drive wheel on the wheelchair.
11. The wheelchair according to claim 10, wherein the separate manual levers can be used to steer the wheelchair.
12. The wheelchair according to claim 9, further comprising multiple CVTs arranged in series for each rear drive wheel.

13. The wheelchair according to claim 9, wherein the hydraulic system further comprises:

- (i) a first piston bounded by a first fluid reservoir and second fluid reservoir;
- (ii) a hydraulically actuated second piston having a pushing fluid reservoir and a pulling fluid reservoir;

wherein application of downward force to the first piston via the manual lever causes fluid to exit from the second fluid reservoir and enter the pulling fluid reservoir, while simultaneously, fluid is pulled into the first fluid reservoir and out of the pushing fluid reservoir, causing the hydraulically actuated second piston to move in a first axial direction away from the CVT; and

wherein application of upward force to the piston via the manual lever causes fluid to exit from the first fluid reservoir and causes enter the pushing fluid reservoir, while simultaneously, fluid is pulled into the second fluid reservoir and out of the pulling fluid reservoir, causing the hydraulically actuated second piston to move in a second axial direction towards the CVT.

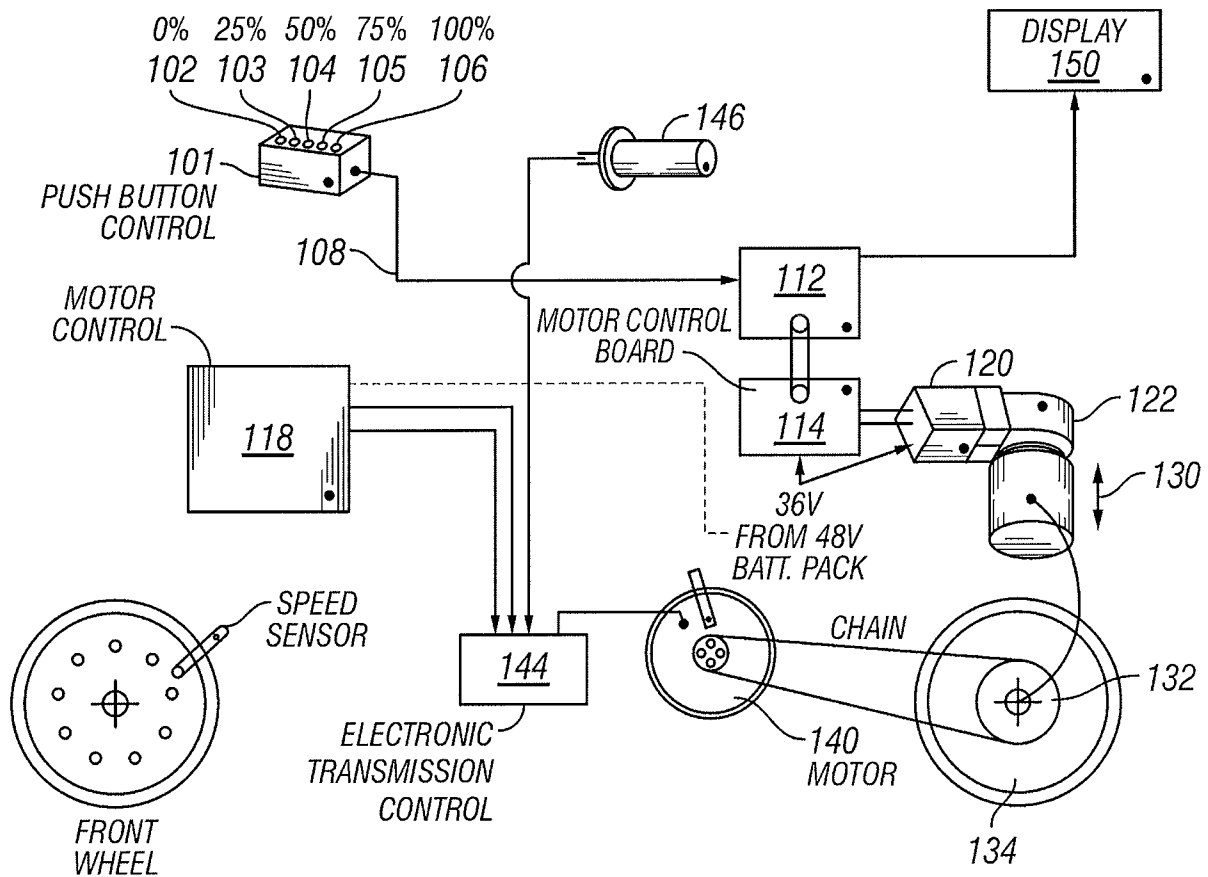


FIG. 1

2/9

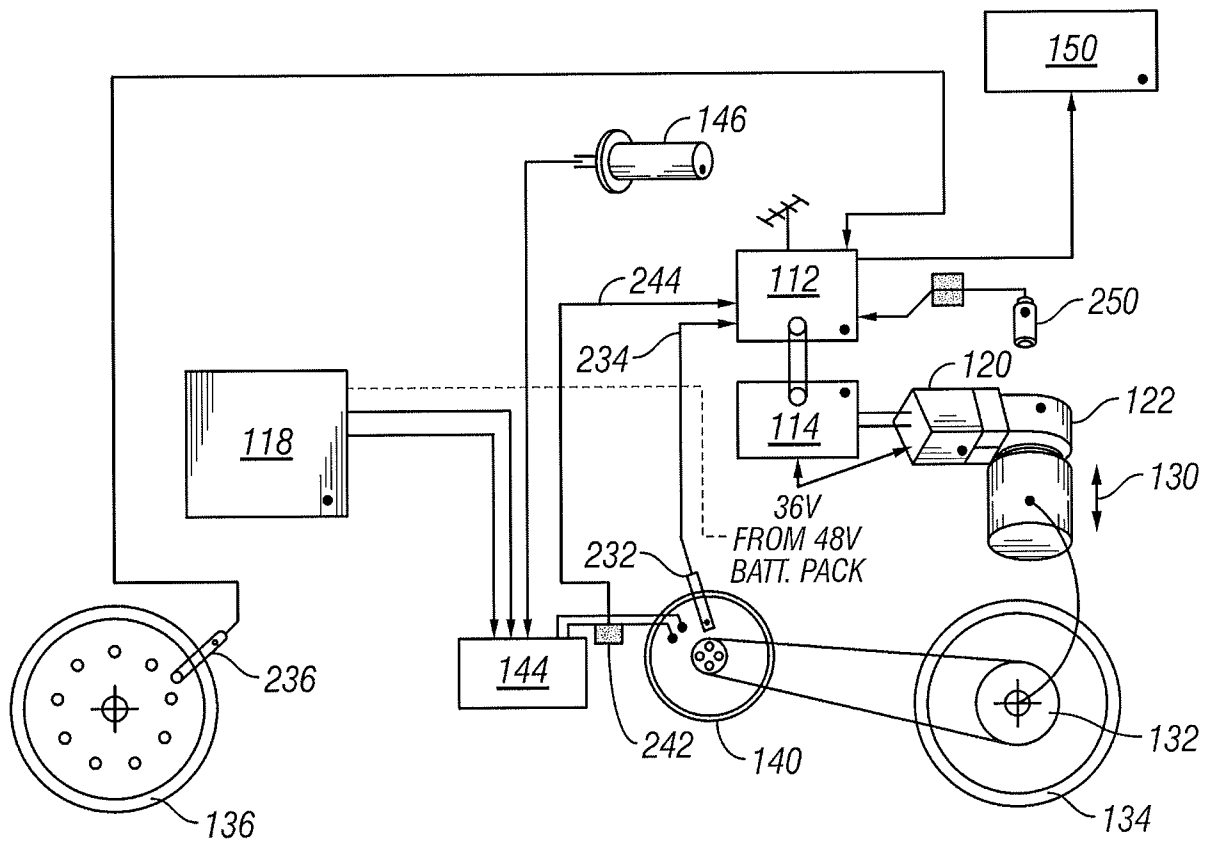


FIG. 2

3/9

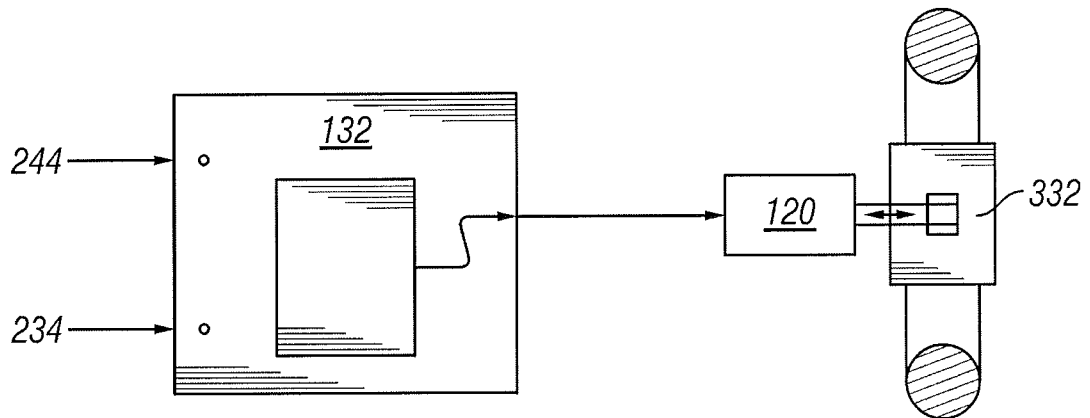


FIG. 3A

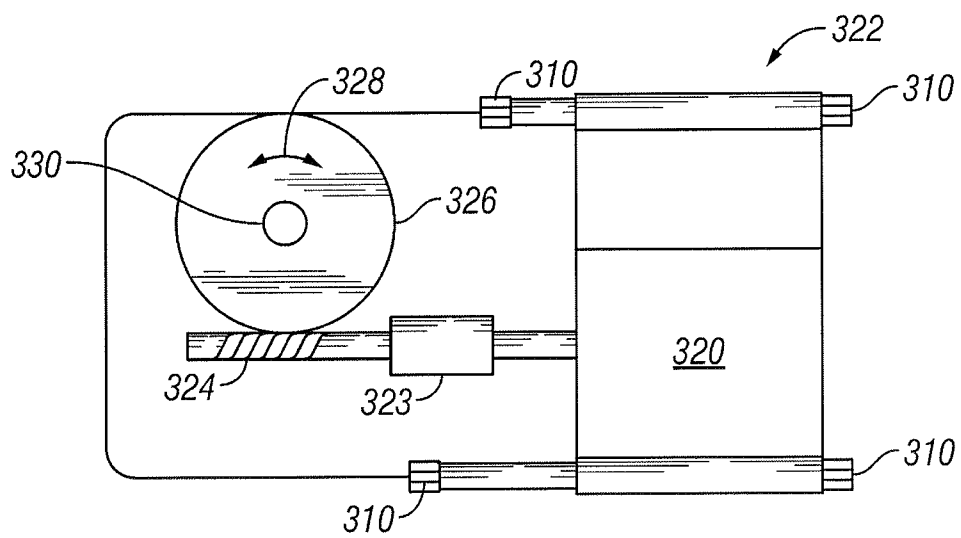


FIG. 3B

4/9

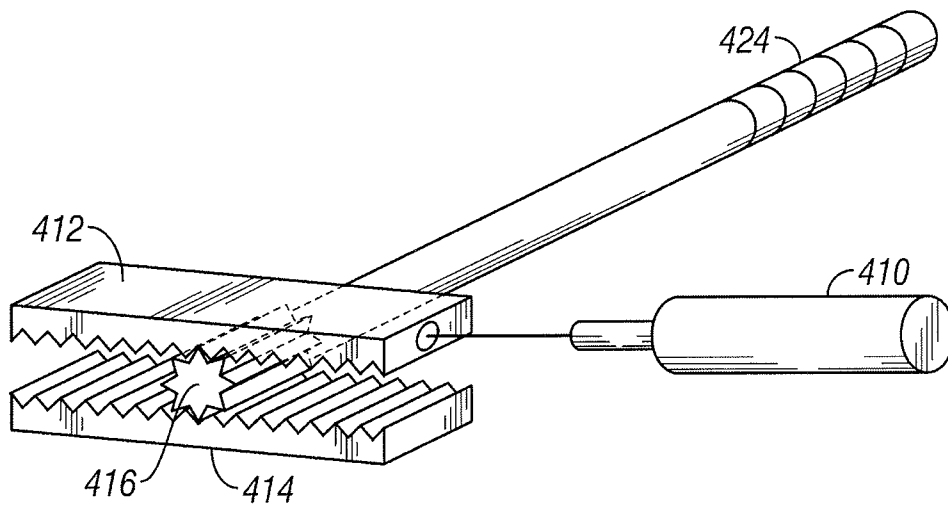


FIG. 4A

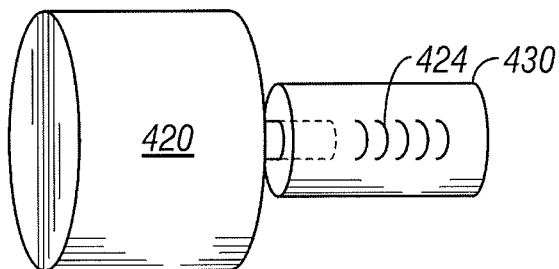


FIG. 4B

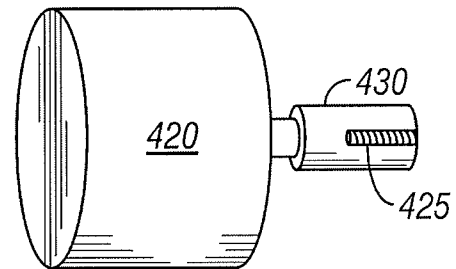


FIG. 4C

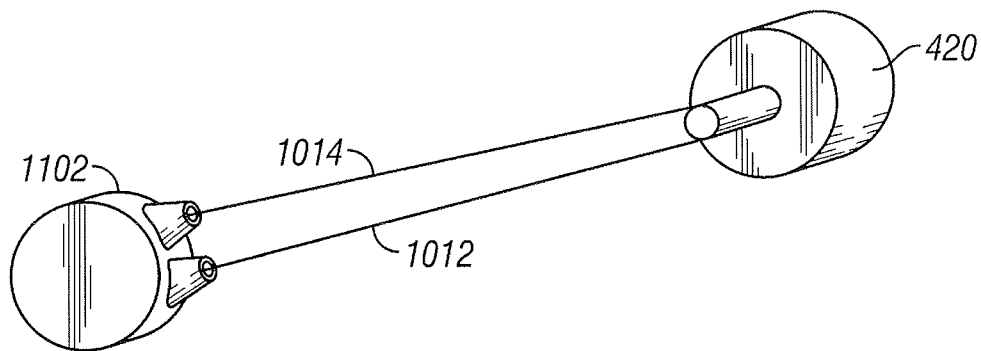


FIG. 4D

5/9

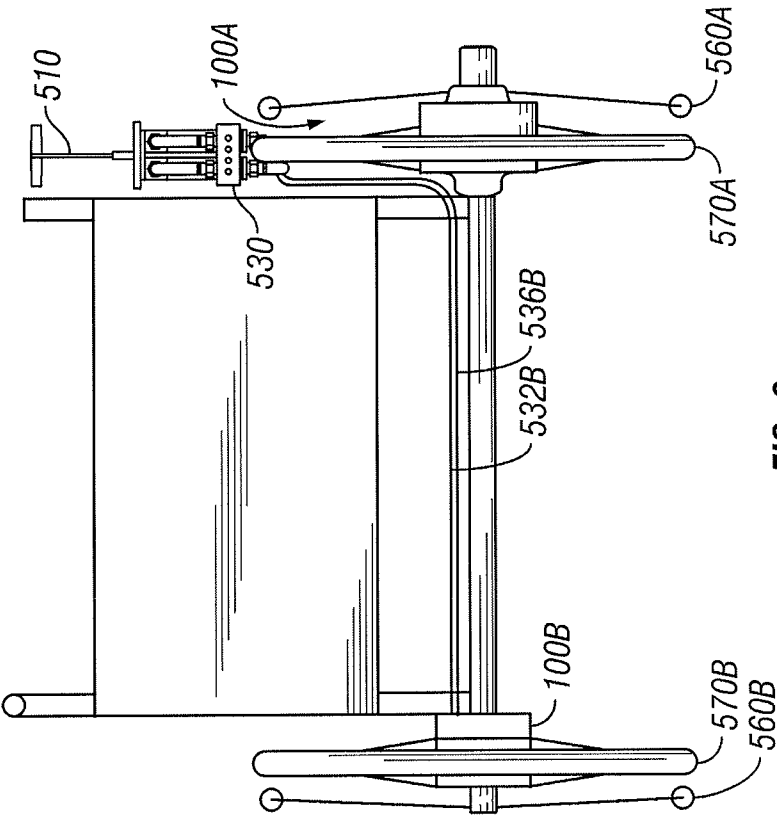


FIG. 6

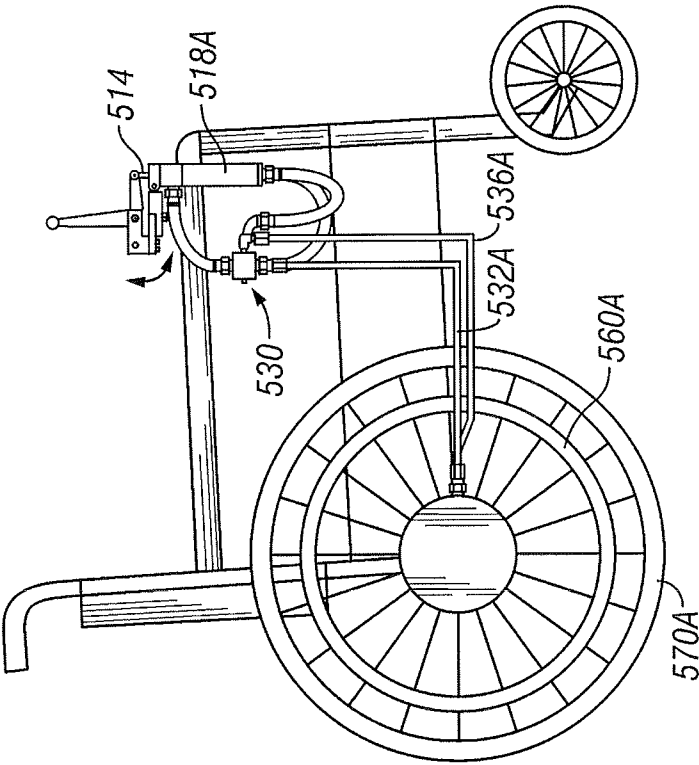


FIG. 5

6/9

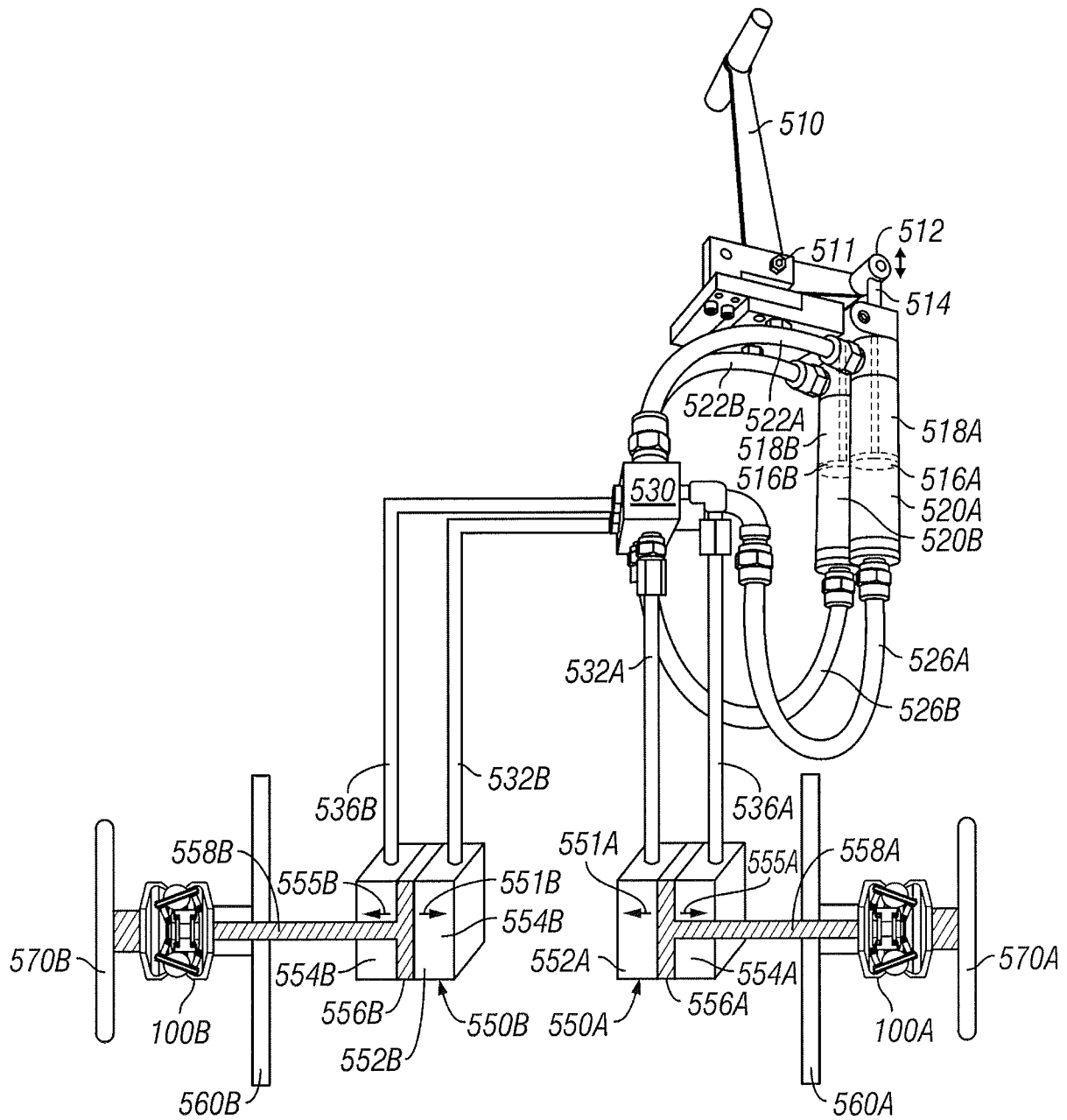


FIG. 7

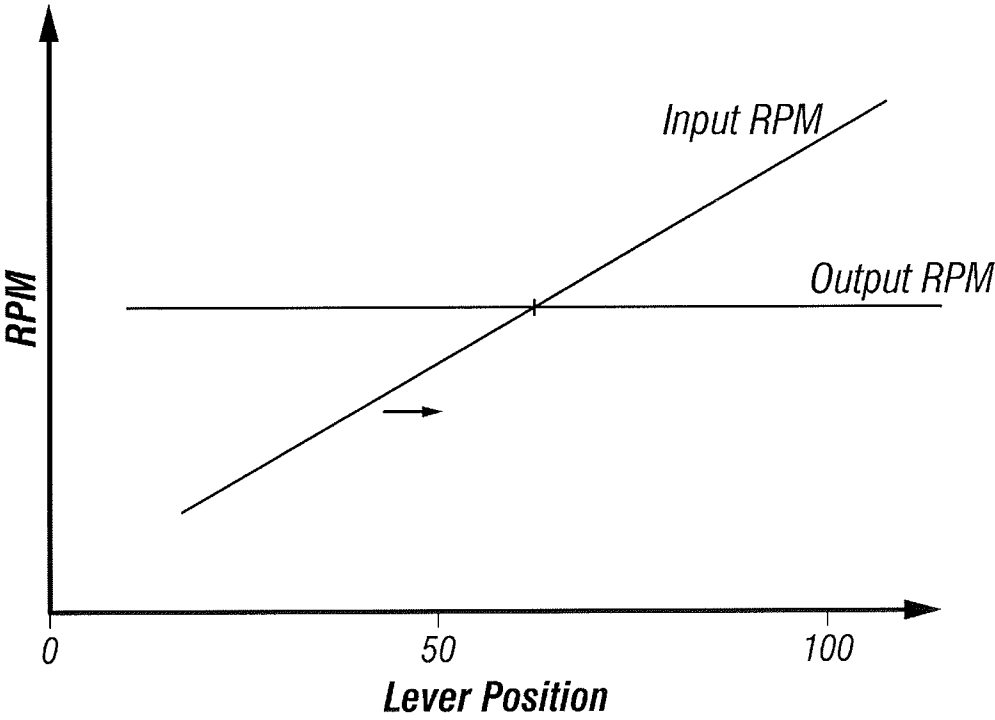


FIG. 8

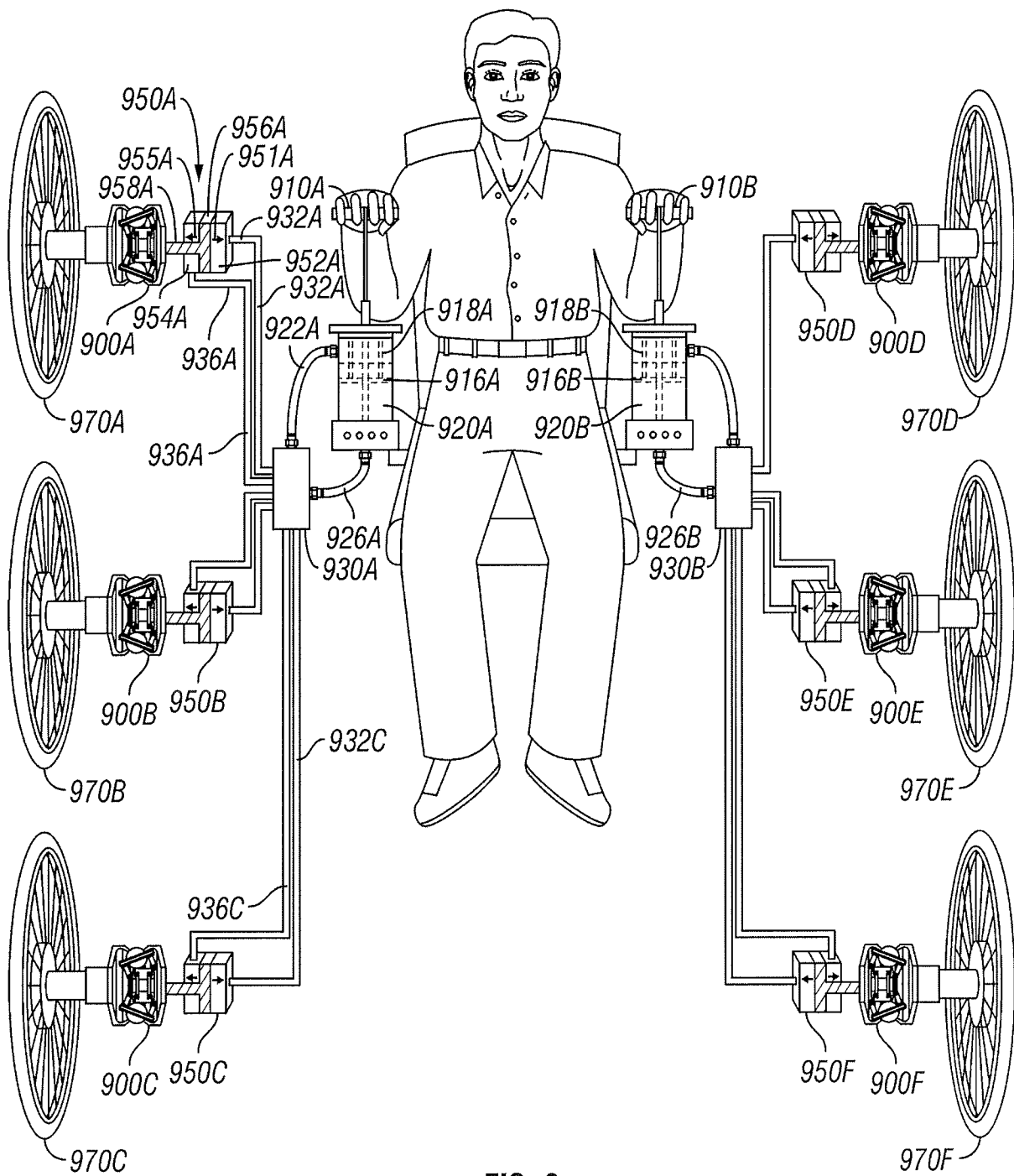


FIG. 9

9/9

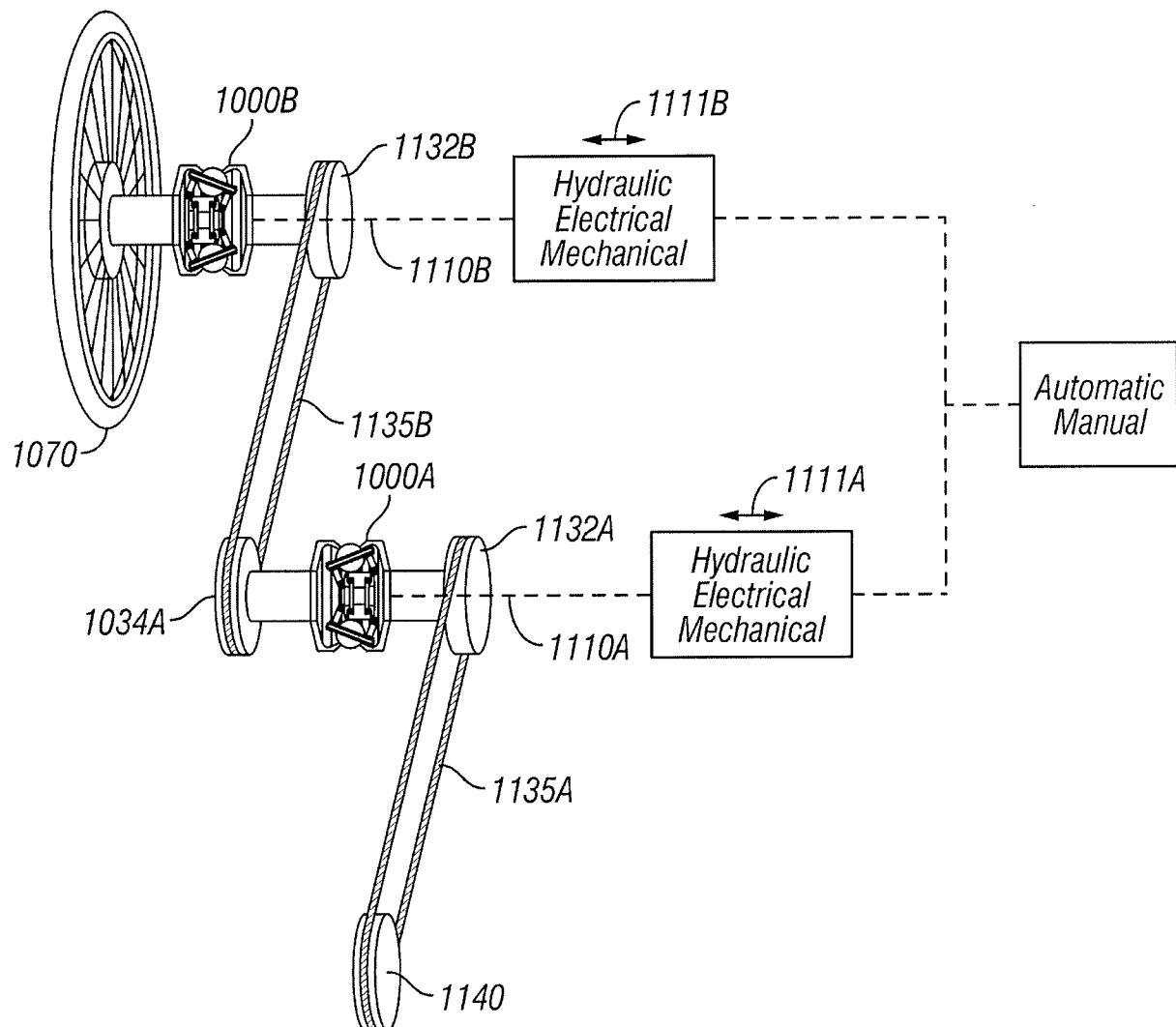


FIG. 10