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(54) Title: METHOD AND SYSTEM FOR NAVIGATING A ROBOTIC GARDEN TOOL

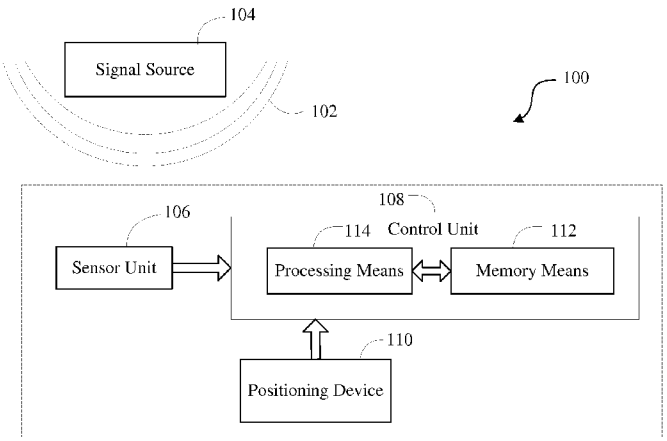


Fig. 1

(57) Abstract: The present invention relates to a method (300) and a system (100) for navigating a robotic garden tool (202) based on one or more operating parameters for subareas (210-218) within the working area (204) and a current location of the robotic garden tool (202). The working area (204) is provided with a signal source (104) corresponding to which a sensor unit (106) is provided in the robotic garden tool (202) for detecting the one or more signals (102) from the signal source (104). The robotic garden tool (202) may include a low-accuracy positioning device (110) for providing co-ordinates of various subareas (210-218) and at any given instant, an approximate location of the robotic garden tool (202). The robotic garden tool (202) further includes a processor means (114) for comparing the coordinates of the subareas (210-218) and the approximate position of the robotic garden tool (202) to determine a current location of the robotic garden tool (202) in the working area (204).

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Method and System for Navigating a Robotic Garden Tool

TECHNICAL FIELD

The present invention relates to a robotic garden tool. In particular, the present invention relates to method and system for navigating the robotic garden tool.

BACKGROUND

The robotic garden tools, such as, but not limited to robotic lawnmowers are widely used for grass cutting applications in a lawn. As these robotic garden tools are autonomous, they have to navigate and keep a track of the areas they have performed operations upon. This is particularly important for the case in which the area to be mowed is very large. If the robotic garden tool does not keep the track of the locations it has performed operations upon and which are the remaining locations, then it may take long time to complete the operation in the whole area.

Normally wires are used to generate reference signals for the robotic garden tool to navigate the robotic garden tool in the lawn. But, the problem with such a system is that the signals generated may not provide any location based information as to where the robotic garden tool currently is. Also, these signals do not provide information as to whether a particular area is mowed and thus it might be possible that the robotic garden tool may mow a particular area multiple times, leading to inefficiency of the complete system.

The technique currently used to avoid the above mentioned problem is the use of navigation systems, such as, Global Positioning System (GPS). The GPS system may provide accurate data as to where the robotic garden tool is, the areas it has performed operations upon, areas remaining, etc. But the problem associated with such system is that it needs expensive GPS trans-receiver to be mounted on the robotic garden tool. Also, the interconnection between the GPS module and the other parts of the robotic garden tool adds to the complexity and the cost of the whole system. Further, if the contact to the GPS system is lost the robotic garden tool may not know its working area limits and might go off boundary.

In light of the foregoing, there is a need for an improved method for navigating the robotic garden tool in the lawn area, which will overcome the disadvantages of complex integration, increased cost, flexibility in cutting, along with optimally providing location based data.

SUMMARY:

In view of the above, it is an objective of the present invention to solve or at least reduce the problems discussed above. In particular, the objective is to provide a method and a system for navigating a robotic garden tool without complex integration.

The objective is at least partly achieved according to the novel method described in claim 1 for navigating a robotic garden tool. The robotic garden tool may operate in a lawn, which has a predetermined working area. Further, the working area may be defined by means of boundaries. The robotic garden tool may inlcude at least one sensor unit to detect the boundaries. Further, the robotic garden tool may be adapted to operate in the working area in an irregular pattern. In an aspect of the present invention, in order to keep the uneven geography in the account, the working area may be divided into various subareas. Further, the robotic garden tool may be provided with a low-accuracy positioning device to define the various subareas based on the coordinates that may be received by the robotic garden tool, for the subareas, from the low-accuracy positioning device. The robotic garden tool may store the co-ordinates of the subareas in a memory means. Further, the robotic garden tool may also receive coordinates for an approximate position of the robotic garden tool from the low-accuracy positioning device. In an aspect of the present invention, the robotic garden tool may be provided with a processor means for comparing the stored coordinates for the subareas with the coordinates for an approximate position of the robotic garden tool from the low-accuracy positioning device and thus, determine in which subarea the robotic garden tool is at present. In an aspect of the present invention, the use of a low-accuracy positioning device may reduce the complexity of integrating an accurate system, as the system does not require a high-accuracy GPS device. Further, this may also reduce the overall cost of the system.

According to claim 2, the robotic garden tool may be provided with one or more operating parameters for each of the subareas. In an aspect of the present invention, the operating parameters may enable to define the various subareas as explained in claims 3-7. By providing the robotic garden tool with operating parameters for each of the subareas, a better operation may be performed by the garden tool. When the robotic garden tool is a robotic lawn mower, the subareas in the lawn may be cut with different parameters providing a lawn cut more precisely according to the wishes of the lawn owner.

According to claim 3, the one or more operating parameters may inlcude cutting heights for each of the subareas. According to claim 4, the one or more operating parameters may inlcude a specific time at which each of the subareas is to be cut. According to claim 5 and 6, the one or more operating parameters may inlcude an order in which the subareas is to be cut or define a time interval between successive cuttings for each of the subareas. According to claim 7, the one or more operating parameters may inlcude restricting the access of the robotic garden tool to different subareas at different times.

According to claim 8, the robotic garden tool may be adapted to generate a low-accuracy map of the working area based on the coordinates for the subareas and the boundaries.

According to claim 9, the robotic garden tool may be adapted to use the generated map to find a remote area within the working area and/or a charging station within the working area. Further, the map may also enable the robotic garden tool to find the shortest path to reach the remote area or the charging station. Thereby, the robotic garden tool may itself keep track of its approximate location within the working area, providing the possibility to navigate to a certain remote area or location.

According to claim 10, the boundaries may define the working area by means of physical fences, fixed objects, a boundary wire, which boundary wire sends electrical signals, and/or through surface determination. Thereby, the outer boundary of the working area may be defined, without using the low-accuracy positioning device.

According to claim 11, the robotic garden tool may be adapted to perform irregular operation within a subarea before continuing to another subarea within the working area.

According to claim 12, in another aspect of the invention, a system may be provided for navigating the robotic garden tool, which may operate in a lawn within a predetermined working area. The working area may be divided into various subareas based on one or more parameters for the subareas and the geography of the working area. The robotic garden tool may be adapted to operate in the working area in an irregular pattern. The system may inlcude a signal source which is adapted to send one or more signals for defining the boundaries of the working area. The system may further inlcude at least one sensor unit to detect the boundaries based on the one or more signals provided by the signal source. Further, the system may inlcude a low-accuracy positioning device for defining the subareas based on the coordinates from the low-accuracy positioning device. The low-accuracy local positioning device may further be adapted to provide an approximate position of the robotic garden tool in a subarea. The system may also be provided with a control unit provided on the robotic garden tool. The control unit may further include at least one processor means and a memory means. In an aspect of the present invention, the processor means may be adapted to compare the coordinates for the subareas with the coordinates for an approximate position of the robotic garden tool from the low-accuracy positioning device and thus, determine in which subarea the robotic garden tool is at present.

According to claim 13, the control unit may be adapted to generate a map based on the coordinates from the low-accuracy positioning device and the one or more signals received from the signal source.

According to claim 14, the control unit may further be adapted to generate one or more commands based at least in part on the location of the robotic garden tool.

According to claim 15, the low-accuracy positioning device may be a standard GPS device.

According to claim 16, the accuracy of the low-accuracy positioning device may be less than ±10m. According to claim 17, the accuracy may be less than ±3m. According

to claim 18, the accuracy may be ±1m. According to claim 19, the accuracy may be less than ±0.1m.

According to claim 20, the robotic garden tool may be a robotic lawnmower.

BRIEF DESCRIPTION OF THE DRAWINGS

The invention will in the following be described in more detail with reference to the enclosed drawings, wherein:

FIG. 1 illustrates a system for navigating a robotic garden tool, according to an embodiment of the present invention;

FIG. 2 illustrates an exemplary lawn, according to an embodiment of the present invention; and

FIG. 3 is a flowchart for illustrating a method for navigating the robotic garden tool, according to an embodiment of the present invention.

DESCRIPTION OF EMBODIMENTS

The present invention will be described more fully hereinafter with reference to the accompanying drawings, in which example embodiments of the invention incorporating one or more aspects of the present invention are shown. This invention may, however, be embodied in many different forms and should not be construed as limited to the embodiments set forth herein; rather, these embodiments are provided so that this disclosure will be thorough and complete, and will fully convey the scope of the invention to those skilled in the art. For example, one or more aspects of the present invention can be utilized in other embodiments and even other types of devices. In the drawings, like numbers refer to like elements.

FIG. 1 illustrates a block diagram of a system **100**, according to an embodiment of the present invention. In an embodiment of the present invention, the system **100** may be embodied in a robotic garden tool for navigating the robotic garden tool around the lawn to be mowed. In an embodiment of the present invention, the robotic garden tool may be adapted to operate in a working area of the lawn in an irregular pattern. In various embodiments of the present invention, the robotic garden tool may be a robotic lawn mower. However, it is apparent to a person who is ordinarily skilled in the art that the

system **100** may also be embodied in any another equipment, such as, but not limited to an automated vacuum cleaner or any other autonomous robotic tool without departing from the scope of the present invention.

In various embodiments of the present invention, the working area of the lawn may be divided into various subareas. Further, in an embodiment of the present invention, the working area of the lawn may be defined by boundaries. In an embodiment of the present invention the boundary may define the working area by means of physical fences, fixed objects, surface determination, a boundary wire and the like. In various embodiments of the present invention, the boundaries may be identified based on one or more signals **102** generated from a signal source **104.** In an embodiment of the present invention, the signal source **104** may be a wire, in particular a boundary wire spread along the perimeter of the working area in the lawn.

As shown in FIG. 1, the robotic garden tool includes a sensor unit **106**, which is adapted to detect the one or more signals **102** from the signal source **104,** as well as other physical objects like fences or fixed objects present in the lawn. In an embodiment of the present invention, the one or more signals **102** include magnetic field signals or electrical current signals from the boundary wire. The sensor unit **106** further includes one or more sensors, such as, but not limited to, a magnetic field sensor, a current sensor, proximity sensor or photoelectric sensor. The sensor unit **106** is positioned at a front portion of the robotic garden tool. In another embodiment of the present invention, the sensors may be positioned at any suitable location on the robotic garden tool.

The sensor unit **106** converts the one or more signals **102** into equivalent electrical signals. Further, the sensor unit **106** provides the converted equivalent electric signals to a control unit **108**, provided in the robotic garden tool, for further processing.

Further as shown in FIG. 1, the system **100** includes a low-accuracy positioning device **110** (herein after referred to as positioning device **110**) in the robotic garden tool. In an embodiment of the present invention, the positioning device **110** may be a standard low-accuracy Global Positioning System (GPS). In an embodiment of the present invention, the positioning device **110** may be a Local Positioning System. In various embodiments of the present invention, the positioning device **110** may be any device

which is capable of providing location based information to the robotic garden tool. In an embodiment of the present invention, the accuracy of the positioning device **110** may be ±10m. In another embodiment of the present invention, the accuracy of the positioning device **110** may be ±3m. In another embodiment of the present invention, the accuracy of the positioning device **110** may be ±1m. In yet another embodiment of the present invention, the accuracy of the positioning device **110** may be ±0.1m.

The positioning device **110** is adapted to provide position co-ordinates of the working area, which is divided into various subareas, to the control unit **108**. The position co-ordinates define the various subareas within the working area. Further, the positioning device **110** is also adapted to provide coordinates for an approximate position of the robotic garden tool to the control unit **108**.

As shown in FIG. 1, the control unit **108** further includes a memory means **112** and a processing means **114**. The control unit **108** stores the position co-ordinates of the subareas, provided by the positioning device **110**, and the converted equivalent electric signals, provided by the sensor unit **106**, in the memory means **112** and/or provide them directly to the processing unit **114**.

The memory means **112** may be a Random Access Memory (RAM), Read Only Memory (ROM), flash memory or any suitable storage equipment. The memory means **112** may include various modules for storing operating instructions and other software of the control unit **108**. The operating instructions may be a set of computer executable instructions for controlling the overall operations of the control unit **108**. The memory means **112** also stores a database of parameters required to send a command to the robotic garden tool based on one or more signals received from the sensor unit **106** and the positioning device **110**. The parameters may also include geometry of the lawn or field, strength of the detected signals, types of detected signals etc. The one or more parameters from the memory means **112** are communicated to the processing means **114** for further processing.

The processing means **114** performs all the computations required to navigate robotic garden tool in different areas of the lawn. The processing means **114** includes an input/output (I/O) interface (not shown), which is operable for receiving the parameters

and the computer executable instructions from the memory means **112**. The processing means **114** also obtains the converted electrical signals from the sensor unit **106** through the I/O interface. In another embodiment of the present invention, the processing means **114** also obtains position co-ordinates from the positioning device **110** through the I/O interface.

The processing means **114** generates a map of the lawn based on the electric signals from the sensor unit **106** and the position co-ordinates of the various subareas within the working area, from the positioning device **110**.

The processor means **114** also receives co-ordinates for an approximate position of the robotic garden tool from the positioning device **110**. Further, the processor means **114** compares the position co-ordinates of the subareas, based on which the map is generated, and the received approximate position of the robotic garden tool to determine a location of the robotic garden tool or especially in which subarea the robotic garden tool is at present. The processor means **114** generates one or more commands based at least in part on the location of the garden tool in the lawn.

The one or more commands are based on various operating parameters defined for each of the subareas in the lawn. The operating parameters are stored in the memory means **112.** The operating parameters may include, but not limited to different cutting heights, certain order in which the subareas should be cut, a specific time in which a subarea should be cut, intervals at which a certain subarea should be cut, restricting the entry of the robotic garden tool in certain subareas at certain times and the like.

The control unit **108** is adapted to use the generated map and the current location of the robotic garden tool to find a remote area where the robotic garden tool should be moved. In an embodiment of the present invention, the remote area may be a charging station for the robotic garden tool, when the battery of the robotic garden tool falls below a pre-determined threshold.

FIG. 2 illustrates a schematic diagram of a lawn **200** for a robotic garden tool **202**, according to an embodiment of the present invention. The robotic garden tool **202** is configured to perform irregular operation within a limited working area **204**. The limited

area may be any terrain with vegetation, such as lawns, gardens, yards, golf courses, fields, and the like.

The lawn **200** may include one or more boundaries which may define the working area **204**. The signal source **104** is provided to delimit the boundary of the working area **204**. In an embodiment of the present invention, the signal source **104** is a boundary wire **206** spread along the perimeter of the working area **204**. The boundary wire **206** may be buried inside the ground. Further, the signal source **104** produces one or more signals **102** for the robotic garden tool **202**. The one or more signals **102** may have particular characteristics associated with it, such as, but not limited to frequency, phase and strength.

The boundaries of the working area **204** may also be defined by fixed objects **208a**, **208b**, and **208c** as shown in FIG. 2, fences (not shown) and the like. Further, the sensor unit **106** is mounted in the robotic garden tool **202**, as explained in conjunction with FIG.1, for detecting one or more signals **102** from the signal source **104** and thus identifying the boundaries of the working area **204**.

To overcome the disadvantages of irregular geography of the working area **204**, the working area **204** is divided into several subareas **210**, **212**, **214**, **216**, and **218** as shown in FIG. 2. To add the subareas based information in the robotic garden tool **202,** the positioning device **110** is provided on the robotic garden tool **202**. The positioning device **110** is used to define the coordinates of the subareas.

The control unit **108** provided in the robotic garden tool **202** is adapted to generate a basic map of the working area **204** based on the position co-ordinates of the subareas received from the positioning device **110** and the one or more converted electric signals received from the sensor unit **106**.

The map may be created automatically. To create the map automatically, the position co-ordinates of the various subareas may be received from the positioning device **110** while the robotic garden tool **202** moves around the working area **204** in an irregular pattern, delimited by the boundary wire **206**. In another embodiment of the present invention, the map may be created manually by an operator. To create the map manually, the robotic garden tool **202** may be placed in different subareas **210-218** on the working

area **204** and then receiving the co-ordinates of the subareas **210-218** from the positioning device **110**. The generated map is stored in the memory means **112** of the control unit **108**.

The generated map may be modified automatically while the robotic garden tool **202** moves within the working area **204** delimited by the boundary wire **206**. The map may consist of a grid structure and the robotic garden tool **202** counts the number of times it traverses through each square in the grid in order to maintain a grid counter. For updating the map and reducing the disturbances, each grid counter may be decremented with a fixed interval. Thus, by evaluating the grid counters, the control unit **108** navigates the robotic garden tool **202** in the working area **204**.

At any given instant, the control unit **108** also receives coordinates of an approximate position of the robotic garden tool **202**. Further, the processor means **114** provided in the control unit **108** compares the position co-ordinates of the subareas **210-218** from the map and the co-ordinates of the approximate position of the robotic garden tool **202** to determine a location of the robotic garden tool **202**. Moreover, the processor means **114** also generates one or more commands based on the location of the robotic garden tool **202** or in which subarea the robotic garden tool **202** is at present.

The working area **204**, delimited by the boundary wire **206**.and/or by fixed objects **208a**, **208b**, and **208c**, is very well defined. The accuracy of the boundary of the working area (the outermost point of the robotic garden tool **202**) will be on a centimeter level. The inaccuracy occurring in a GPS receiver is principally stochastically distributed within a circle around the point where the robotic garden tool **202** is actually positioned. When information is collected over time regarding the positions the robotic garden tool **202** "thinks" it has been positioned, a map having quite fuzzy edges is obtained, which map includes also points outside of the real working area. Since the inaccuracy is stochastically distributed, the number of points outside of the boundary wire **206** will be far fewer than inside of the boundary wire **206**. This means that by applying simple filters to the "raw" map, (such as a requirement that there should be a certain number of hits on a particular point for that point to be regarded as within the working area) a map having considerably higher accuracy than what is received by means of the direct GPS signal.

Hence, a very accurate map may be obtained, although the robotic garden tool **202** does not know exactly where it is positioned.

The one or more commands are based at least in part on one or more operating parameters that may be pre-defined for each of the subareas **210-218**. An operating parameter may define a specific height of the grass to be cut in a certain subarea. In another embodiment of the present invention, an operating parameter may be the priority or the order in which the subareas should be cut or may define a specific order in which the robotic garden tool **202** should cut the subareas **210-218**. In another embodiment of the present invention, an operating parameter may define the time interval between successive mowing over a particular subarea. In an embodiment of the present invention, an operating parameter may be time and days on which each subarea should be mowed. In another embodiment of the present invention, an operating parameter may define criteria in which mowing over a certain subarea is restricted entirely or for a specific period of time. In still another embodiment of the present invention, an operating parameter may define the speed at which the robotic garden tool **202** may cut certain subareas **210-218**. This may be helpful to reduce the speed of cutting where more obstacles are present or reducing the speed in narrower areas. Further, in an embodiment of the present invention, the various operating parameters may ensure that all subareas **210-218** are mowed as desired.

By selecting where the robotic garden tool **202** should start operating and by "instructing" the tool to turn around when it comes to an area which is already well cut, an evenly distributed mowing of the whole working area may be obtained. One way of ensuring that the entire working area is evenly cut is to instruct the robotic garden tool **202** to head for the subarea having the fewest number of hits, when it leaves the charging station. The robotic garden tool **202** will be able to reach that subarea since the generated map is so accurate. In this way, the robotic garden tool **202** will know with a fairly high accuracy how far it has to follow the boundary wire **206** in order to reach the part of the working area which has been visited the fewest number of times.

The generated map, the operating parameters and the approximate position of the robotic garden tool **202** enables the control unit **108** to navigate the robotic garden tool

202 to the charging station **220**, when the battery level of the robotic garden tool falls below a predefined threshold. The control unit **108** is adapted to navigate the robotic garden tool **202** through the shortest path to the charging station **220**.

An operating parameter may define a security feature in which the control unit **108** disables the operations of the robotic garden tool **202**, if the robotic garden tool **202** is placed at a location which is not identified in the generated map.

The above parameters may be programmed into the control unit **108**, and the control unit **108** further saves the parameters into the memory means **112**.

FIG. 3 illustrates a flow chart of a method **300** for navigating a robotic garden tool in the working area, according to an embodiment of the present invention. In step **302,** the working area **204** is divided into several subareas **210**, **212**, **214**, **216**, and **218**. The working area **204** of the lawn **200** is defined by boundaries. The boundary defines the working area by means of physical fences, fixed objects, surface determination, a boundary wire or the like. The boundaries may be identified based on one or more signals **102** generated from a signal source **104**. The signal source **104** is a wire, in particular the boundary wire **206** spread along the perimeter of the working area **204** in the lawn **200**.

The robotic garden tool **202** includes a sensor unit **106**, which is adapted to detect the one or more signals **102** from the signal source **104,** as well as other physical objects like fences or fixed objects present in the lawn **200**.

Further, in step **304**, the robotic garden tool **202** is provided with the positioning device **110**. The positioning device **110** may be a standard Global Positioning System (GPS) with low accuracy, or a Local Positioning System. In various embodiments of the present invention, the positioning device **110** may be any device which is capable of providing location based information to the robotic garden tool **202**.

The positioning device **110** is adapted to provide position co-ordinates of the working area **204** based on which the working area **204** is defined into various subareas **210-218**.

In step **306**, the robotic garden tool **202** stores the position co-ordinates of the working area **204** in the memory means **112** of the control unit **108** provided in the

robotic garden tool **202**. Further, the robotic garden tool **202** also stores the converted electric signals received from the sensor unit **106**.

The robotic garden tool **202** is adapted to generate a map of the lawn **202** based on the converted electric signals from the sensor unit **106** and the position co-ordinates of the working area **204** from the positioning device **110**.

In step **308**, the processor means **114** provided on the robotic garden tool **202** receives co-ordinates for an approximate position of the robotic garden tool **202** from the positioning device **110**.

Further, in step **310**, the processor means **114** compares the position co-ordinates of the subareas **210-218**, based on which the map is generated, and the received approximate position of the robotic garden tool **202** to determine a location of the robotic garden tool **202** or especially in which subarea the robotic garden tool **202** is at present.

The processor means **114** generates one or more commands based at least in part on the location of the robotic garden tool **202** in the lawn **200**. The one or more commands are based on one or more operating parameters defined for each of the subareas **210-218** in the lawn **200**. The operating parameters are stored in the memory means **112.** The operating parameters may include, but not limited to different cutting heights, certain order in which the subareas should be cut, a specific time in which a subarea should be cut, intervals at which a certain subarea should be cut, restricting the entry of the robotic garden tool **202** in certain subareas **210-218** at certain times and the like.

The control unit **108** is adapted to use the generated map and the current location of the robotic garden tool **202** to find a remote area where the robotic garden tool **202** should be moved. The remote area may be the charging station **220** for the robotic garden tool **202**, when the battery of the robotic garden tool **202** falls below a pre-determined threshold.

Though the above mentioned invention explains the working with respect to robotic garden tool **202**, a person skilled in the art may know that such a system may be

easily implemented on other tools like, but not limited to, robotic lawnmower or automated vacuum cleaners.

In the drawings and specification, there have been disclosed preferred embodiments and examples of the invention and, although specific terms are employed, they are used in a generic and descriptive sense only and not for the purpose of limitation, the scope of the invention being set forth in the following claims.

CLAIMS:

1. A method (**300**) for navigating a robotic garden tool (**202**) operating in a lawn (**200**) within a predetermined working area (**204**) defined by boundaries, which robotic garden tool (**202**) is provided with at least one sensor unit (**206**) adapted to detect the boundaries, and wherein the robotic garden tool (**202**) is adapted to operate in the working area (**204**) in an irregular pattern,

the method comprising the steps of:

dividing the working area (**204**) into subareas (**210-218**);

providing the robotic garden tool (**202**) with a low-accuracy positioning device (**110**) for defining the subareas (**210-218**) based on coordinates from the low-accuracy positioning device (**110**) in the robotic garden tool (**202**);

storing the coordinates for the subareas (**210-218**) in the robotic garden tool (**202**),

receiving coordinates for an approximate position of the robotic garden tool (**202**) from the low-accuracy positioning device (**110**); and

providing the robotic garden tool (**202**) with a processor means (**114**) for comparing the stored coordinates for the subareas (**210-218**), with the coordinates for an approximate position of the robotic garden tool (**202**) from the low-accuracy positioning device (**110**), to determine in which subarea the robotic garden tool (**202**) is at present.

2. A method (**300**) according claim 1 further comprising the step of providing the robotic garden tool (**202**) with one or more operating parameters for each of the subareas (**210-218**).

3. A method (**300**) according to claim 2, wherein the one or more operating parameters comprises cutting heights for each of the subareas (**210-218**).

4. A method (**300**) according to claim 2, wherein the one or more operating parameters comprises a specific time at which each of the subareas (**210-218**) is to be cut.

5. A method (**300**) according to claim 2, wherein the one or more operating parameters comprises an order in which the subareas (**210-218**) is to be cut.

6. A method (**300**) according to claim 2, wherein the one or more operating parameters is the time intervals between successive cuttings for each of the subareas (**210-218**).

7. A method (**300**) according to claim 2, wherein the one or more operating parameters comprises restricting the access of the robotic garden tool (**202**) to different subareas (**210-218**) at different times.

8. A method (**300**) according to claim 1 or 2 further comprising the step of generating a low-accuracy map of the working area based on the coordinates for the subareas (**210-218**) and the boundaries.

9. A method (**300**) according to claim 8, wherein the robotic garden tool (**202**) is adapted to use the generated map to find a remote area within the working area (**204**) and/or a charging station within the working area (**204**).

10. A method (**300**) according to any of the preceding claims, wherein the boundaries defines the working area (**204**) by means of physical fences, fixed objects, a boundary wire (**206**), which boundary wire (**206**) sends electrical signals, and/or through surface determination, wherein the at least one sensor unit (**106**) on the robotic garden tool (**202**) is adapted to detect the boundaries.

11. A method (**300**) according to any of the preceding claims, wherein the robotic garden tool (**202**) is adapted to perform irregular operation within a subarea before continuing to another subarea within the working area (**204**).

12. A system (**100**) for navigating a robotic garden tool (**202**) operating in a lawn (**200**) within a predetermined working area (**204**) defined by boundaries, which working

area (**204**) is divided into subareas (**210-218**), wherein the robotic garden tool (**202**) is adapted to operate in the working area (**204**) in an irregular pattern, the system (**100**) comprising:

a signal source (**104**), adapted to send one or more signals (**102**) for defining the boundaries of the working area (**204**);

at least one sensor unit (**106**) provided on the robotic garden tool (**202**) to detect the boundaries based on the one or more signals (**102**) provided by the signal source (**104**);

a low-accuracy positioning device (**110**) for defining the subareas (**210-218**) based on the coordinates from the low-accuracy positioning device (**110**), and wherein the low-accuracy local positioning device (**110**) is further adapted to provide an approximate position of the robotic garden tool (**202**) in a subarea; and

a control unit (**108**) provided on the robotic garden tool (**202**), where in the control unit (**108**) comprises at least one processor means (**114**) and a memory means (**112**);

characterized in that

the processor means (**114**) is adapted to compare the coordinates for the subareas (**210-218**) with the coordinates for an approximate position of the robotic garden tool (**202**) from the low-accuracy positioning device (**110**), to determine in which subarea the robotic garden tool (**202**) is at present.

13. A system (**100**) according to claim 12, wherein the control unit (**108**) is adapted to generate a map based on the coordinates from the low-accuracy positioning device (**110**) and the one or more signals (**102**) received from the signal source (**104**).

14. A system (**100**) according to claim 12, wherein the control unit (**108**) is adapted to generate one or more commands based at least in part on the location of the robotic garden tool (**202**).

15. A system (**100**) according to any of the preceding claims, wherein the low-accuracy positioning device (**110**) is a standard GPS device.

16. A system (**100**) according to any of the preceding claims, wherein the accuracy of the low-accuracy positioning device (**110**) is less than ±10m.

17. A system (**100**) according to any of the preceding claims, wherein the accuracy of the low-accuracy positioning device (**110**) is less than ±3m.

18. A system (**100**) according to any of the preceding claims, wherein the accuracy of the low-accuracy positioning device (**110**) is less than ±1m.

19. A system (**100**) according to any of the preceding claims, wherein the accuracy of the low-accuracy positioning device (**110**) is less than ±0.1m.

20. A system (**100**) according to any of the preceding claims, wherein the robotic garden tool (**202**) is a robotic lawnmower.

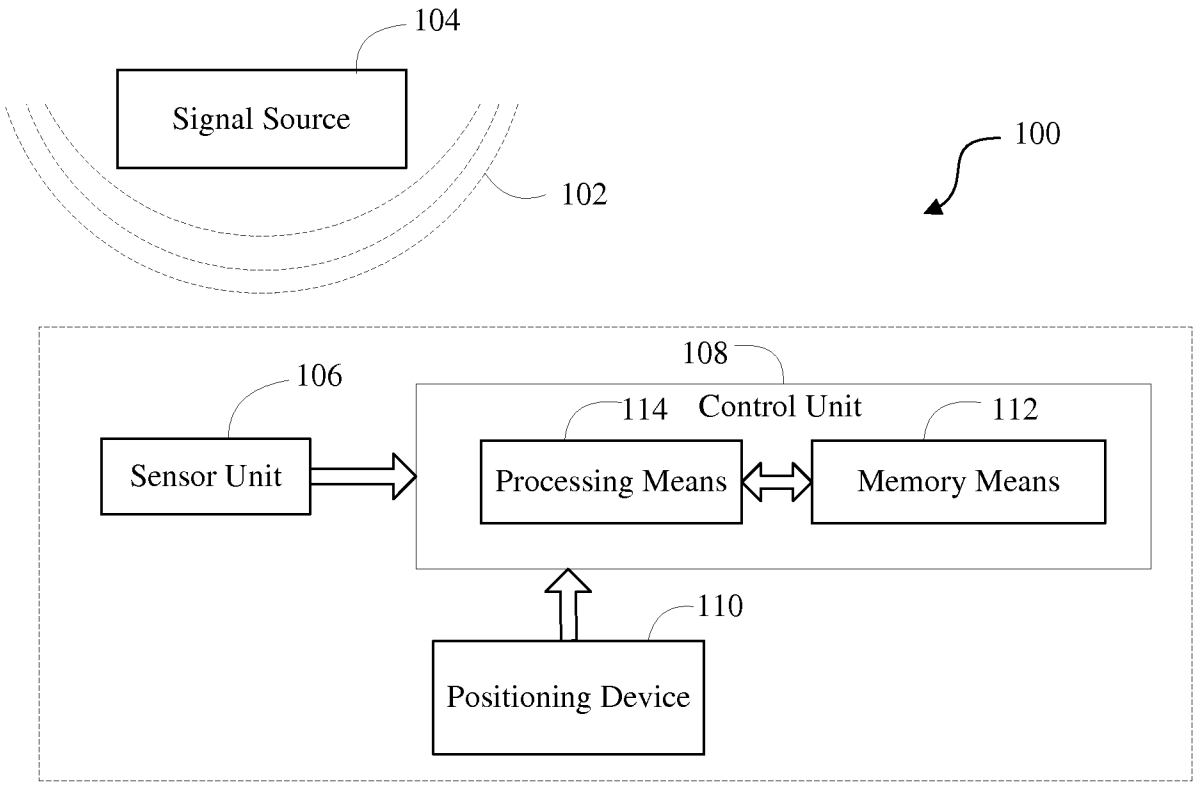

104
Signal Source
102
100
108
106
114
Control Unit
112
Sensor Unit
Processing Means
Memory Means
110
Positioning Device

Fig. 1

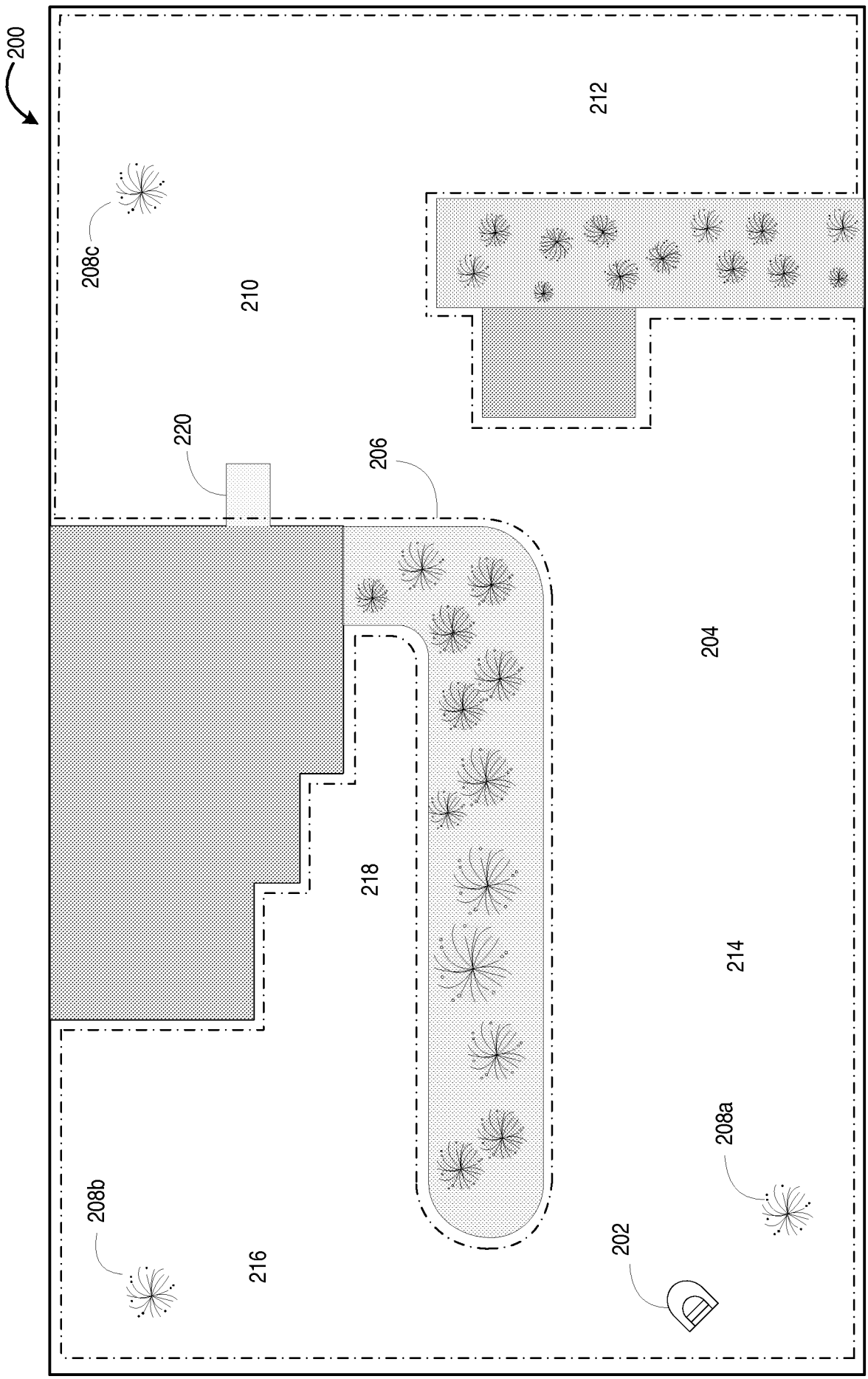


Fig. 2

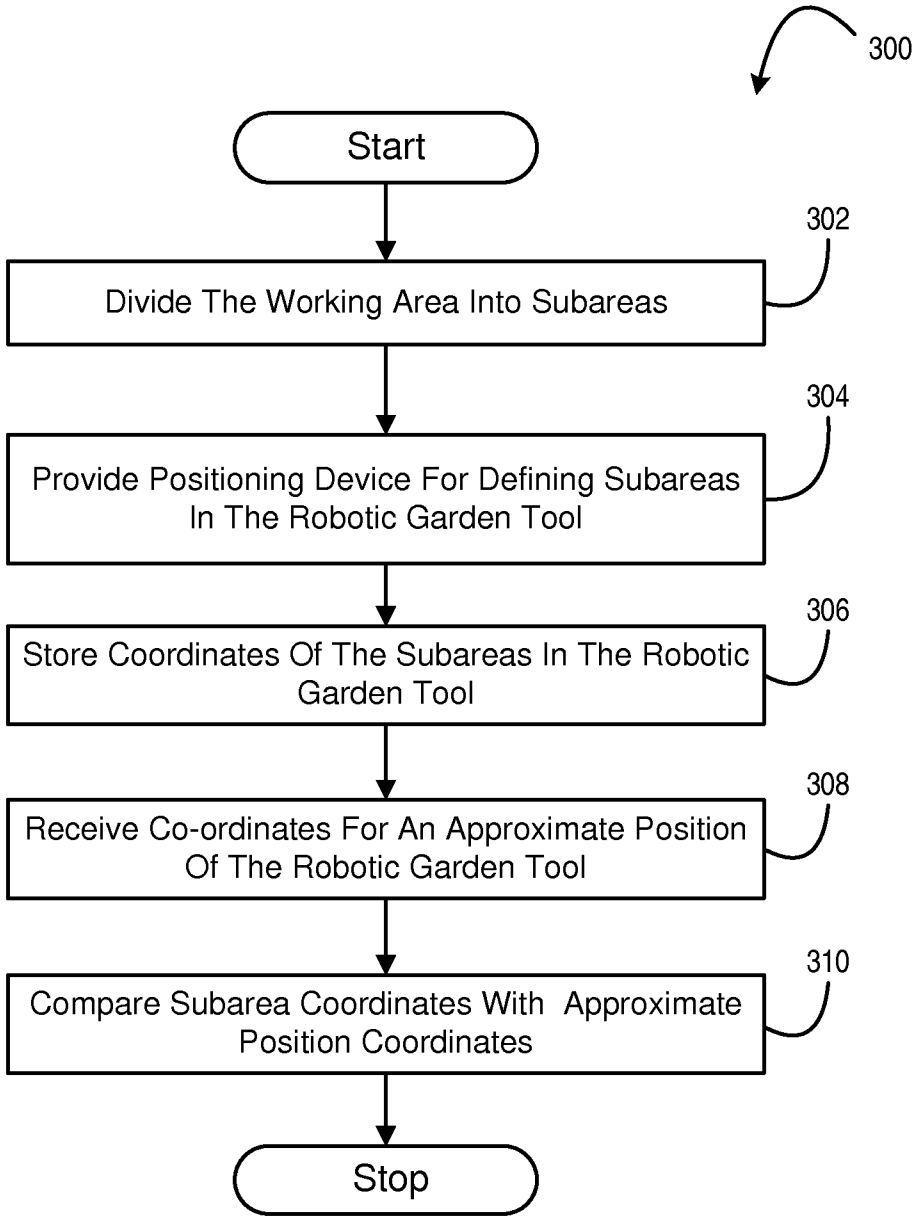

300
Start
302
Divide The Working Area Into Subareas
304
Provide Positioning Device For Defining Subareas In The Robotic Garden Tool
306
Store Coordinates Of The Subareas In The Robotic Garden Tool
308
Receive Co-ordinates For An Approximate Position Of The Robotic Garden Tool
310
Compare Subarea Coordinates With Approximate Position Coordinates
Stop

Fig. 3

INTERNATIONAL SEARCH REPORT

International application No.
PCT/SE2011/050291

A. CLASSIFICATION OF SUBJECT MATTER

IPC: see extra sheet

According to International Patent Classification (IPC) or to both national classification and IPC

B. FIELDS SEARCHED

Minimum documentation searched (classification system followed by classification symbols)

IPC: A01D, G05D

Documentation searched other than minimum documentation to the extent that such documents are included in the fields searched

SE, DK, FI, NO classes as above

Electronic data base consulted during the international search (name of data base and, where practicable, search terms used)

EPO-Internal, PAJ, WPI data

C. DOCUMENTS CONSIDERED TO BE RELEVANT

Category*	Citation of document, with indication, where appropriate, of the relevant passages	Relevant to claim No.
X	US 7343230 B2 (MCMURTRY RICHARD ET AL), 11 March 2008 (2008-03-11); abstract; column 1, line 64 - column 1, line 65; column 3, line 65 - column 4, line 15; column 4, line 1 - column 4, line 38; column 4, line 39 - column 5, line 28; figures 1,2,3,12; claim 1 --	1-20
X	US 20080039991 A1 (MAY REED R ET AL), 14 February 2008 (2008-02-14); abstract; figures 1,2; paragraph 0026 --	1-20
A	US 5086535 A1 (GROSSMEYER MARK ET AL), 11 February 1992 (1992-02-11); abstract; figures 1,4 --	1-20

☒ Further documents are listed in the continuation of Box C. ☒ See patent family annex.

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Date of the actual completion of the international search	Date of mailing of the international search report
24-05-2011	24-05-2011
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INTERNATIONAL SEARCH REPORT

International application No.
PCT/SE2011/050291

C (Continuation). DOCUMENTS CONSIDERED TO BE RELEVANT

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A	US 5204814 A1 (NOONAN THOMAS H ET AL), 20 April 1993 (1993-04-20); abstract; figures 1,5 --- --------	1-20

Continuation of: second sheet

International Patent Classification (IPC)

A01D 34/00 (2006.01)
G05D 1/02 (2006.01)

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Cited literature, if any, will be enclosed in paper form.

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