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DE-A1- 19 819 406
GB-A- 2 147 682
US-A- 5 018 545

The invention relates to a sewer rehabilitation method, wherein

- a rehabilitation tool is introduced, by means of a robot that can be moved in a sewer main line of a sewerage system, into a house sewer line leading into said sewer main line,
- 5 - rehabilitation work is carried out in the house sewer line by means of the rehabilitation tool, and
- the rehabilitation tool is removed from the house sewer line by means of the robot once rehabilitation work is completed.
- 10 Furthermore, the invention relates to a sewer rehabilitation system comprising a robot that can be moved in a sewer main line of the sewerage system and a rehabilitation tool that can be introduced into a house sewer line.

The term of sewer rehabilitation is understood to mean methods, techniques, and
15 measures for restoring or improving existing sewerage systems. Sewers must be so planned, built, maintained and operated that the structural status is sustained over their service life. By way of a sewer rehabilitation, the functional capability of a sewerage system is restored and its service life is extended. Sewer rehabilitation methods cover repair, revamping and renewal methods.

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For rehabilitation of house sewer lines, suitable rehabilitation tools, for example a milling tool and/or a lining tool bridging a defective point by means of a so-called hose liner, are conventionally introduced, starting from a house revision shaft. This approach bears a disadvantage in that it requires access to the private property, although in numerous
25 cases the house sewer line leading up to the building falls into the rehabilitation competence of the relevant municipality.

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EP 1 070 905 A2 discloses a device for performing canal works, wherein a tool is connected via a flexible sleeve to a device carrier.

GB 2 147 682 A describes a robot unit for use in underground lines, with a gripping arm rotatable relative to the body of the robot unit.

DE 198 19 406 A1 discloses a device for rinsing channels, with a arranged on a trolley
35 rinsing hose, which can be inserted into a house connection channel.

WO 2012/016322 A1 describes a sewer rehabilitation system with a plurality of tools, wherein the tools are arranged on cables or hoses.

DE 37 30 315 A1 discloses a method and a device for rehabilitating a sewer pipe,
5 wherein a shut-off bubble is moved, inflated and secured by a pivotable gripper into an inlet.

US 5 018 545 A describes a device for cleaning of channels, wherein a cleaning nozzle is arranged via a hose to a body.

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EP 2 287 510 A1 describes a system for the permanent closure of a branch line.

Known from DE 103 11 828 A1 is a sewer rehabilitation method in which a suitable rehabilitation device is introduced from a sewer main line by means of a device that can
15 be moved through the main sewer line to the branch line of the relevant house sewer line. To this effect, the mobile device comprises a deflection channel. The device is fixable in the area of the branch in the sewer main line. By means of the deflection channel, it is possible to introduce rehabilitation tools, rehabilitation material and the like from the sewer main line into the house sewer line in order to perform rehabilitation work
20 required there. An essential point in this prior art sewer rehabilitation method lies in that the mobile device comprises a housing with an inflatable packer, by means of which the transition between the deflection channel and the branch of the house sewer line can be sealed and the mobile device can be fixed.

25 The mentioned printed publication leaves it open how precisely the rehabilitation tool is introduced through the deflection channel of the mobile device into the house sewer line. A disadvantage with the afore-mentioned sewer rehabilitation method lies in that a special device, that means the movable device with the packer and deflection channel is needed. This implies additional expenditure and accordingly higher cost.

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Against this background, it is the object of the present invention to provide a practical and low-cost sewer rehabilitation method and a corresponding system that allow for performing a sewer rehabilitation in a house sewer line by starting from a main sewer line.

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This object is achieved by the present invention on the basis of a sewer rehabilitation method of the initially specified type in that the robot has a remotely controllable gripping member for receiving the rehabilitation tool, wherein the robot and the rehabilitation tool via separate cables from day to day supplied with energy and remotely controlled,

5 wherein the robot

- picks up the rehabilitation tool by the remotely controllable gripping member and transports it through the sewer main line to the mouth of the house sewer line,

- introduces the rehabilitation tool into the house sewer line and puts it down,

- advances the rehabilitation tool into the house sewer line up to a defective point,

10 by moving back into the main pipe after putting down the refurbishment tool, then grabbing the repair tool's cable and finally pulling up again in the main pipe, and

- retracts the rehabilitation tool from the house sewer line and picks it up again once rehabilitation work is completed.

15 Thus it is the key idea of the present invention to utilize the robot movable in the sewerage system to pick up the rehabilitation tool, and to transport it, for example, from a shaft of the sewer main line through the sewer main line up to the mouth of the house sewer line. Furthermore, the robot introduces the rehabilitation tool into the house sewer line and puts it down there. Moreover, the robot inventively advances the rehabilitation

20 tool in the house sewer line to the defective point to be treated. Finally, the robot again retracts the rehabilitation tool from the house sewer line and picks it up once the rehabilitation work is completed.

Suitable for use as movable robot in the sense of the present invention is a sewer

25 rehabilitation robot of actually known construction type and function. Known from prior art are sewer rehabilitation robots which can be moved in a sewer on wheels driven by means of an electrical, pneumatic or hydraulic motor. Sewer rehabilitation robots of this type are supplied with energy and remotely controlled via a cable from above-ground. They are provided with an electrically, pneumatically or hydraulically driven rehabilitation

30 device, for example a milling head, by means of which the rehabilitation work can be performed in remotely monitored and remotely controlled manner. A video camera integrated into the sewer rehabilitation robot is typically provided for remote monitoring.

Such a sewer rehabilitation robot is inventively applied, by replacing the rehabilitation

35 device with a remotely controllable gripping member which takes-up the rehabilitation tool that is independent from the the robot and which is then introduced by the robot

into the house sewer line and put down there. Thus, a conventional sewer rehabilitation robot can be adapted to suit the inventive application at low expenditure.

Suitable for use as rehabilitation tool for the inventive application is a milling robot known from prior art and commercially available which is conventionally utilized for carrying-out milling work, starting from the house revision shaft. Such a milling robot can be utilized inventively without any modifications or adaptations. Likewise, the rehabilitation tool may be an actually known and commercially available lining tool for introduction of a hose liner.

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A substantial advantage of the inventive sewer rehabilitation method thus lies in that existing, proven and low-cost devices obtainable on the market can be utilized which just need to be slightly adapted. Inasmuch as a conventional sewer rehabilitation robot and a milling robot are already available, it is merely required to retrofit the sewer rehabilitation robot to be able to accommodate the milling robot. Thus, the inventive sewer rehabilitation method that enables performing rehabilitation work in the house sewer line by starting from the sewer main line can be made available and applied at conceivably low cost.

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Preferably, the robot introduces the rehabilitation tool at least 50 cm deep, further preferably at least 1 m deep, especially preferably at least 2 m deep into the house sewer line before it puts it down there. The robot should introduce the rehabilitation tool at least so deep into the house sewer line that it does not fall again out from it into the sewer main line. The remotely controllable gripping member of the robot should be dimensioned accordingly.

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In an embodiment according to the invention, the robot and the rehabilitation tool are supplied with energy and remotely controlled via separate cables from above-ground. As mentioned before, it is common practice for sewer rehabilitation robots of conventional construction type to supply them with energy and control them remotely via cables. In this sense, a cable should be understood to mean any type of a flexible connection that transfers energy and remote control signals. Typically, several lines, that means multicore electrical lines as well as compressed-air lines, if any (in case that pneumatic drives are applied) or hydraulic lines (in case that hydraulic drives are applied) are grouped together in the cable. In accordance with the invention, as mentioned before, a (modified) conventional sewer rehabilitation robot in combination

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with a conventional milling robot can be applied. Conventional sewer rehabilitation robots and milling robots each comprise an individual cable link connecting to an energy supply and remote control equipment located above ground.

- 5 With an embodiment according to the invention of the sewer rehabilitation method, the robot advances the rehabilitation tool in the house sewer line up to the defective point to be rehabilitated in a manner that it moves backward after putting down the rehabilitation tool in the sewer main line, then grabs the cable of the rehabilitation tool and finally moves forward again in the sewer main line. This procedure can be repeated
10 several times, depending on how far the rehabilitation tool is to be advanced in the house sewer line. On moving backward, the cable of the rehabilitation tool is let loose by the robot. On advancing, the cable of the rehabilitation tool is grabbed in order to transfer the thrust to the rehabilitation tool via the (accordingly flexurally rigid) cable as the robot advances. For grabbing the cable of the rehabilitation tool, the afore-mentioned remotely
15 controllable gripping member of the robot can be used. Other types of a detachable fixation of the cable at the robot are conceivable.

The object of the present invention is furthermore achieved by way of a sewer rehabilitation system that comprises a robot which can be moved in the sewer main line
20 of a sewerage system and a rehabilitation tool which can be introduced into a house sewer line. In accordance with the invention, the robot comprises a remotely controllable gripping member by means of which the rehabilitation tool can be grabbed, wherein a cable of the remedial tool is grippable by the remotely controllable gripping member, wherein the cable of the remedial tool is rigid and transmits a thrust exerted by the robot
25 on the cable to the rehabilitation tool. The sewer rehabilitation system is suitable for executing the inventive sewer rehabilitation method described hereinabove.

As mentioned before, the robot and the rehabilitation tool can preferably be supplied with energy and remotely controlled via separate cables.

30 According to the invention, not only the rehabilitation tool but also a cable of the rehabilitation tool can be grabbed by the remotely controllable gripping member. This has the advantage that the gripping member can be utilized on the one hand for transporting the rehabilitation tool through the sewer main line up to the house sewer
35 line mouth into the sewer main line, and on the other hand for advancing the rehabilitation tool in the house sewer line in a manner, as described above, that the

robot grabs the cable of the rehabilitation tool and transfers a thrust via the flexurally rigid cable onto the rehabilitation tool by advancing in the sewer main line.

With a preferred embodiment of the inventive sewer rehabilitation system, a cable duct is provided for which guides the cable of the rehabilitation tool at the robot. The cable duct ensures that the cable of the rehabilitation tool is not damaged, for example due to a contact with the drive wheels of the robot. Besides, the cable duct assures that the cable of the rehabilitation tool can be grabbed reliably and securely by the gripping member of the robot for advancing the rehabilitation tool in the house sewer line.

According to the invention, the gripping member of the robot comprises a claw-type gripper provided with gripping claws that move toward and away from each other. A claw-type gripper is suitable for grabbing most different objects with most different dimensions. Thus, a claw-type gripper can be applied with special flexibility. In particular, a claw-type gripper is well suitable on the one hand for grabbing the rehabilitation tool in order to transport it up to the mouth of the house sewer line and to introduce it into the house sewer line according to the present invention, and on the other hand for grabbing the cable of the rehabilitation tool in order to advance it in the house sewer line. According to the invention, the claw-type gripper comprises two interlockable groups of gripping claws, wherein at least one group comprises at least two gripping claws. Preferably, both groups comprise two (or more) gripping claws which are mounted in staggered arrangement toward each other so that in interlocked status they overlap each other at least partly in a direction perpendicular to the plane of movement of the gripping claws. The interlockable groups of gripping claws have the advantage that objects having clearly different diameters can be grabbed thereby reliably with sufficient high gripping force. On the one hand, the rehabilitation tool can be retained reliably and securely. On the other hand, the cable of the rehabilitation tool can be grabbed with sufficient firmness so that the thrust required for advancing the rehabilitation tool in the house sewer line can be transferred from the robot to the cable.

Practical examples of the invention are elucidated in the following by way of drawings, where:

Figures 1a-1c: show a schematic view of the inventive method;

Figure 2: is a schematic view of the inventive sewerage rehabilitation system with a mobile robot and milling tool;

Figure 3: shows a gripping member of the inventive robot.

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Figures 1a to 1c illustrate the inventive sewer rehabilitation method schematically. A robot 2 is introduced through a shaft 1 into a sewer main line 3 of a sewerage system. Robot 2 comprises a gripping member 4 whose configuration is described further below in greater detail. By means of gripping member 4, robot 2 holds a milling tool 5. Robot 10 2 is linked via a cable 6 to a vehicle 7 located above ground. Vehicle 7 is provided with facilities for remote control and energy supply of robot 2. Via a cable 8 provided separately from cable 6, the milling tool 5 is linked to vehicle 7 so that also the energy supply and remote control of milling tool 5 proceed from vehicle 7. Robot 2 can be moved via motor-driven wheels in the sewer main line 3 and transports milling too 5 through 15 sewer main line 3 to a house sewer line 9 leading into sewer main line 3. As illustrated in Figure 1b, robot 2 introduces milling tool 5 by means of its gripping member 4 into house sewer line 9 and puts it down there. It means that the gripping member 4 of robot 2 releases the milling tool 5 in the house sewer line 9. When robot 2 has put down the milling tool 5 in the house sewer line 9, it moves backward in the sewer main line 3. 20 Then it grabs cable 8 of milling tool 5 and again advances in sewer main line 3. Via the flexurally rigid cable 8, thrust is transferred to milling tool 5 so that it is advanced in the house sewer line 9 up to a defective point 10 that requires treatment. Upon its arrival at the defective point 10, the milling tool 5, remotely controlled from vehicle 7, performs the milling work required for rehabilitation. For this purpose, the milling tool 5 like robot 2, 25 too, comprise a video camera (not illustrated here). Via the video camera of robot 2 and milling tool 5, the movements of robot 2 in the sewer main line 3 and the movements of milling tool 5 in the house sewer line 9 can be monitored from vehicle 7 in order to remotely operate robot 2 and milling tool 5 independently of each other. Upon completion of the milling work, robot 2 retracts the milling tool 5 from the house sewer 30 line 9 back to the mouth of the house sewer line 9 into the sewer main line 3 (not illustrated here) until robot 2 can again pick up the milling tool 5 by means of its gripping member 4. Subsequently, robot 2 transports the milling tool 5 back to shaft 1 where it can be taken out from the sewerage system together with robot 2.

35 Figure 2 shows the inventive sewer rehabilitation system in greater detail. The system comprises the robot 2 which can be moved in the sewer main line 3 via motor-driven

(e.g. pneumatically) wheels 11. At its front side, robot 2 comprises a bearing block 12 that is motorically rotatable about axis M. Arranged at the bearing block 12 is a jib 14 that can be motorically slewed about an axis 13. Arranged at the end of jib 14 is a claw-type gripper 16 that can be motorically slewed about another axis 15. The claw-type gripper 16 holds the milling tool 5, as illustrated in Figure 2. The bearing block with the jib 14, slewing axes 13 and 15 and with the claw-type gripper 16 form the gripping member 4 of robot 2. The jib 14 is amply sized so that the milling tool 5 can be introduced by robot 2 at least 50 cm, better at least 1 m deep into the house sewer line 9 before it can be put down there. Otherwise there is a risk that the milling tool 5 falls out after having been put down in the sewer main line 3. Owing to the rotatability of bearing block 12 and because of slewability about both axes 13 and 15, it results a high mobility of the gripping member 4 so that the milling tool 5 can be introduced reliably into the sewer main line 9, i.e. practically for every geometry of the mouth of the house sewer line 9 leading into the sewer main line 3. Cable ducts 17 are provided at the housing of robot 2 which guide the cable 8 of milling tool 5 at robot 2. Cable ducts 17 ensure that cable 8 does not get in contact with the wheels 11 of robot 2 whereby it could be damaged. Furthermore, the cable duct 17 assures that the cable 8 for advancing of the milling tool 5 in the house sewer line 9 can be securely grabbed by the claw-type gripper 16.

Figure 3 shows a view of the claw-type gripper 16. Claw-type gripper 16 comprises gripping claws 18, 19 that can be moved toward and away from each other. The gripping claws 18 and 19 each form a group of interlockable gripping claws. Figure 3 shows the gripping claws 18, 19 in interlocked status in which the gripping claws partly overlap each other. To allow for movement toward and away from each other, the gripping claws 18 are slewable about a slewing axis 20 and the gripping claws 19 are slewable about a slewing axis 21. Because of the interlockability of gripping claws 18, 19, objects with substantially different diameter can be grabbed. This is important because by means of the claw-type gripper 16 it is feasible to grab both the milling tool 5 and the cable 8 of the milling tool 5 reliably and with sufficient gripping force.

PATENTKRAV

1. Kanalsaneringsfremgangsmåde, hvor

- 5 - et saneringsværktøj (5) ved hjælp af en robot (2), som kan bevæges i en hovedledning (3) i et spildevandskanalsystem, indføres i en i hovedledningen (3) udmundende hustilslutningsledning (9),
- ved hjælp af saneringsværktøjet (5) gennemføres saneringsarbejder i hustilslutningsledningen (9), og
- 10 - saneringsværktøjet (5) bliver efter afslutning af saneringsarbejderne, ved hjælp af robotten (2) atter fjernet fra hustilslutningsledningen (9),
- hvor robotten (2) omfatter et fjernstyrbart gribeorgan (4) til optagelse af saneringsværktøjet (5), idet robotten (2) og saneringsværktøjet (5) via separate kabler (6, 8) forsynes med energi og fjernstyres fra over jorden, idet robotten (2)
- 15 - optager saneringsværktøjet (5) ved hjælp af det fjernstyrbare gribeorgan og transporterer dette igennem hovedledningen (3) frem til udmundingen for hustilslutningsledningen (9),
- indfører og afsætter saneringsværktøjet (5) i hustilslutningsledningen (9),
- fremskyder saneringsværktøjet (5) i hustilslutningsledningen (9) frem til en
- 20 beskadiget position (10), idet den efter afsætningen af saneringsværktøjet (5) kører tilbage i hovedledningen (3), derefter griber kablet (8) til saneringsværktøjet (5) og til slut atter kører frem i hovedledningen (3), og
- efter afslutning af saneringsarbejderne trækker saneringsværktøjet (5) tilbage fra hustilslutningsledningen og atter optager dette.

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2. Kanalsaneringsfremgangsmåde ifølge krav 1, **kendetegnet ved, at** robotten (2) indfører saneringsværktøjet (5) i det mindste 50 cm, fortrinsvis i det mindste 1 m, særligt foretrukket i det mindste 2 m ind i hustilslutningsledningen (9), før den afsætter dette der.

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3. Kanalsaneringssystem med en i en hovedledning (3) i et spildevandskanalsystem bevægelig robot (2) og et i en hustilslutningsledning (9) indførbart saneringsværktøj (5), hvor robotten (2) omfatter et fjernstyrbart gribeorgan (4), hvormed saneringsværktøjet (5) kan gribes, idet et kabel (8) for saneringsværktøjet (5) kan gribes ved hjælp af det

35 fjernstyrbare gribeorgan (4), idet kablet (8) for saneringsværktøjet (5) er bøjningsstift og kanalsaneringssystemet er udformet således, at kablet (8) overfører et af robotten (2)

på kablet udøvet skub til saneringsværktøjet (5), idet gribeorganet (4) omfatter en kloformet griber (16), med i retning mod hinanden og bort fra hinanden bevægelige gribeklør (18, 19), idet den kloformede griber (16) omfatter to grupper af gribeklør (18, 19), som kan sammenblades indbyrdes, idet i det mindste én af grupperne omfatter i

5 det mindste to gribeklør.

4. Kanalsaneringssystem ifølge krav 3, **kendetegnet ved, at** robotten (2) og saneringsværktøjet (5) via separate kabler (6, 8) kan forsynes med energi og fjernstyres.

10 5. Kanalsaneringssystem ifølge krav 4, **kendetegnet ved** en kabelføring (17), som fører kablet (8) for saneringsværktøjet (5) på robotten (2).

6. Kanalsaneringssystem ifølge ethvert af kravene 3 til 5, **kendetegnet ved, at** robotten (2) og saneringsværktøjet (5) hver især omfatter et videokamera.

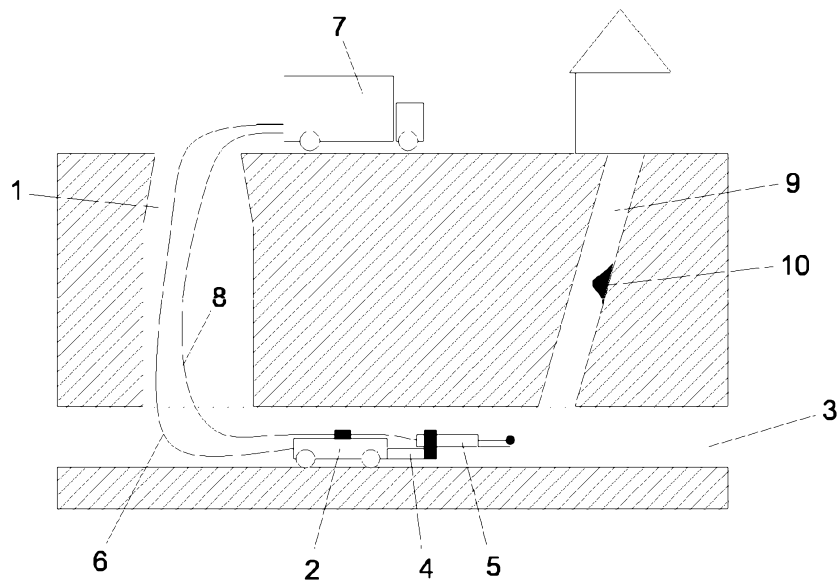


Fig. 1a

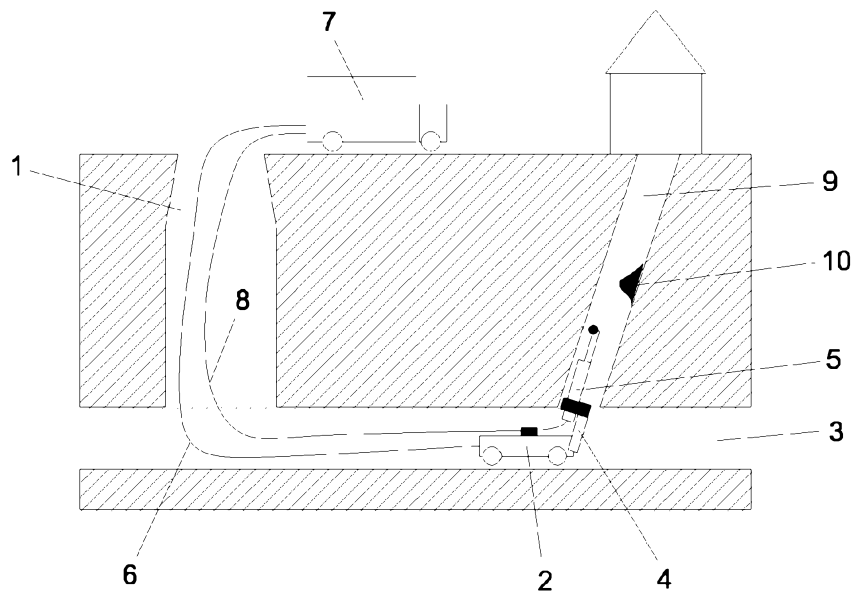


Fig. 1b

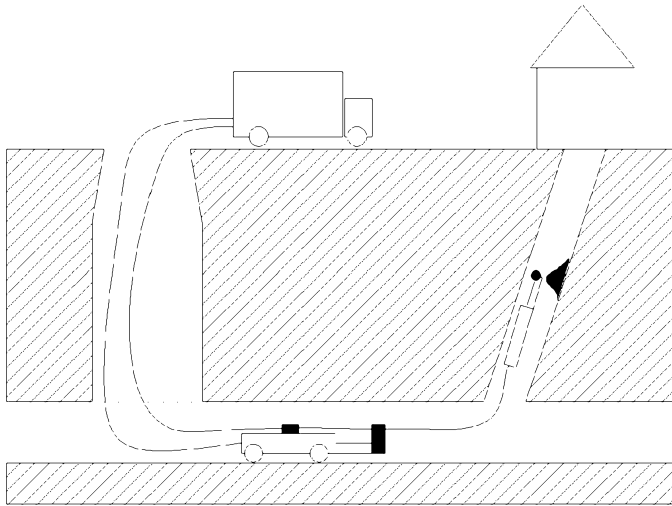


Fig. 1c

