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STADIE, Robert Rolf, , Hatfield, Hertfordshire, AL10 9UL, Storbritannien
- (74) Fuldmægtig i Danmark: **Inspicos P/S, Agern Allé 24, 2970 Hørsholm, Danmark**
- (54) Benævnelse: **ROBOTIC SERVICE DEVICE AND HANDLING METHOD**
- (56) Fremdragne publikationer:
WO-A1-2013/167907
NO-B1- 317 366
ANONYMOUS: "An introduction to the AutoStore Concept", HATTELAND, 1 January 2006 (2006-01-01), pages 1 - 36, XP055819983, Retrieved from the Internet <URL:www.hateland.com/autostore> [retrieved on 20210701]

DESCRIPTION

Description

[0001] The present invention relates to top level of a frame structure.

[0002] This application claims priority from UK Patent Application no. GB1404870.6 filed on 18th March 2014.

[0003] Some commercial and industrial activities require systems that enable the storage and retrieval of a large number of different products. One known type of system for the storage and retrieval of items in multiple product lines involves arranging storage bins or containers in stacks on top of one another, the stacks being arranged in rows. The storage bins or containers are accessed from above, removing the need for aisles between the rows and allowing more containers to be stored in a given space.

[0004] Methods of handling containers stacked in rows have been well known for decades. In some such systems, for example as described in US 2,701,065, to Bertel comprise freestanding stacks of containers arranged in rows in order to reduce the storage volume associated with storing such containers but yet still providing access to a specific container if required. Access to a given container is made possible by providing relatively complicated hoisting mechanisms which can be used to stack and remove given containers from stacks. The cost of such systems are, however, impractical in many situations and they have mainly been commercialised for the storage and handling of large shipping containers.

[0005] The concept of using freestanding stacks of containers and providing a mechanism to retrieve and store specific containers has been developed further, for example as described in EP 0 767 113 B to Cimcorp. '113 discloses a mechanism for removing a plurality of stacked containers, using a robotic load handler in the form of a rectangular tube which is lowered around the stack of containers, and which is configured to be able to grip a container at any level in the stack. In this way, several containers can be lifted at once from a stack. The movable tube can be used to move several containers from the top of one stack to the top of another stack, or to move containers from a stack to an external location and vice versa. Such systems can be particularly useful where all of the containers in a single stack contain the same product (known as a single-product stack).

[0006] In the system described in '113, the height of the tube has to be as least as high as the height of the largest stack of containers, so that that the highest stack of containers can be extracted in a single operation. Accordingly, when used in an enclosed space such as a warehouse, the maximum height of the stacks is restricted by the need to accommodate the tube of the load handler.

[0007] EP 1037828 B1 (Autostore) describes a system in which stacks of containers are arranged within a frame structure. A system of this type is illustrated schematically in Figures 1 to 4 of the accompanying drawings. Robotic load handling devices can be controllably moved around the stack on a system of tracks on the upper most surface of the stack.

[0008] One form of robotic load handling device is further described in Norwegian patent number 317366. Figure 3(a) and 3(b) are schematic perspective views of a load handling device from the rear and front, respectively, and Figure 3(c) is a schematic front perspective view of a load handling device lifting a bin.

[0009] A further development of load handling device is described in UK Patent Application No 1314313.6 where each robotic load handler only covers one grid space, thus allowing higher density of load handlers and thus higher throughput of a given size system.

[0010] WO2013/167907 discloses a storage system suitable for storing multiple product lines in an automated warehouse environment. The storage system comprises a top level of a frame structure having the features in the preamble of claim 1.

[0011] In some implementations of such bin handling systems, there can be a very large number of robotic load handling devices running on a single grid. These load handling devices can experience problems from time to time and require repair or other intervention in order to return to useful service. Furthermore, there may be spillages or a build-up of dirt or dust on the grid which will require cleaning.

[0012] It is a disadvantage of the prior art systems described above that in order to rescue a faulty load handling device or in order to clean the grid, a user is required to access the grid on the stack and perform the necessary operations manually to fix or remove the load handling device or to clean the grid.

[0013] For these operations to happen safely it is necessary to stop all robotic load handlers on the grid before the user is allowed access. The higher the number of robotic load handlers in use and the larger the grid, the higher the likelihood of faults occurring and an increased consequence of each fault, due to the number of units which have to be stopped.

[0014] According to the invention there is provided a top level of a frame structure according to claim 1.

[0015] The invention will now be described with reference to the accompanying diagrammatic drawings in which

Figure 1 is a schematic perspective view of a frame structure for housing a plurality of stacks of bins in a known storage system;

Figure 2 is a schematic plan view of part of the frame structure of Figure 1;

Figures 3(a) and 3(b) are schematic perspective views, from the rear and front respectively, of one form of robotic load handling device for use with the frame structure of Figures 1 and 2, and Figure 3(c) is a schematic perspective view of the known load handler device in use lifting a bin;

Figure 4 is a schematic perspective view of a known storage system comprising a plurality of load handler devices of the type shown in Figures 3(a), 3(b) and 3(c), installed on the frame structure of Figures 1 and 2, together with a robotic service device.

Figure 5 is a schematic perspective view of a robotic service device on a frame structure according to one embodiment of the present invention;

Figure 6 is a schematic perspective view of part of the service device of Figure 5, showing a latch mechanism and camera means positioned on the said robotic service device;

Figures 7a and 7b are schematic side views of the robotic service device of Figures 5 and 6 showing the wheels, drive system and a cleaning mechanism;

Figure 8 is a schematic perspective view of the robotic service device of Figures 5 to 7, in use, collecting a malfunctioning load handling device;

Figure 9 is an enlarged view of a latching mechanism suitable for latching the malfunctioning load handling device to the robotic service device;

Figure 10 is a schematic perspective view of a robotic service device on a frame structure according to the embodiment of the invention, the service device being substantially bridge-shaped;

Figures 11 is a schematic side view of the robotic service device of Figure 10, showing the service device in situ over a malfunctioning load handling device;

Figure 12 is a schematic perspective view of a robotic service device on a frame structure according to the embodiment of the invention, the service device being substantially u-shaped;

Figure 13 is a schematic perspective view of a robotic service device, a plurality of service devices operating so as to engage a malfunctioning service device to move it or remove it from the grid;

Figure 14 is a schematic perspective drawing of a robotic service device of Figure 13 showing a different configuration of the plurality of service devices;

Figure 15 is a schematic perspective drawing of a robotic service device of Figure 13, showing a further configuration of the plurality of service devices; and

Figure 16 is a schematic perspective view of a robotic service device, in which the service device is provided with a seat to enable carriage of a passenger or user.

[0016] As shown in Figures 1 and 2, stackable containers, known as bins 10, are stacked on top of one another to form stacks 12. The stacks 12 are arranged in a grid frame structure 14 in a warehousing or manufacturing environment. Figure 1 is a schematic perspective view of the frame structure 14, and Figure 2 is a top-down view showing a single stack 12 of bins 10 arranged within the frame structure 14. Each bin 10 typically holds a plurality of product items (not shown), and the product items within a bin 10 may be identical, or may be of different product types depending on the application.

[0017] The frame structure 14 comprises a plurality of upright members 16 that support horizontal members 18, 20. A first set of parallel horizontal members 18 is arranged perpendicularly to a second set of parallel horizontal members 20 to form a plurality of horizontal grid structures supported by the upright members 16. The members 16, 18, 20 are typically manufactured from metal. The bins 10 are stacked between the members 16, 18, 20 of the frame structure 14, so that the frame structure 14 guards against horizontal movement of the stacks 12 of bins 10, and guides vertical movement of the bins 10.

[0018] The top level of the frame structure 14 includes rails 22 arranged in a grid pattern across the top of the stacks 12. Referring additionally to Figures 3 and 4, the rails 22 support a plurality of robotic load handling devices 30. A first set 22a of parallel rails 22 guide movement of the load handling devices 30 in a first direction (X) across the top of the frame structure 14, and a second set 22b of parallel rails 22, arranged perpendicular to the first set 22a, guide movement of the load handling devices 30 in a second direction (Y), perpendicular to the first direction. In this way, the rails 22 allow movement of the load handling devices 30 in two dimensions in the X-Y plane, so that a load handling device 30 can be moved into position above any of the stacks 12.

[0019] Each load handling device 30 comprises a vehicle 32 which is arranged to travel in the X and Y directions on the rails 22 of the frame structure 14, above the stacks 12. A first set of wheels 34, consisting of a pair of wheels 34 on the front of the vehicle 32 and a pair of wheels 34 on the back of the vehicle 32, are arranged to engage with two adjacent rails of the first set 22a of rails 22. Similarly, a second set of wheels 36, consisting of a pair of wheels 36 on each side of the vehicle 32, are arranged to engage with two adjacent rails of the second set 22b of rails 22. Each set of wheels 34, 36 can be lifted and lowered, so that either the first set of wheels 34 or the second set of wheels 36 is engaged with the respective set of rails 22a, 22b at any one time.

[0020] When the first set of wheels 34 is engaged with the first set of rails 22a and the second set of wheels 36 are lifted clear from the rails 22, the wheels 34 can be driven, by way of a drive mechanism (not shown) housed in the vehicle 32, to move the load handling device 30 in the X direction. To move the load handling device 30 in the Y direction, the first set of wheels 34 are lifted clear of the rails 22, and the second set of wheels 36 are lowered into engagement with the second set of rails 22a. The drive mechanism can then be used to drive the second set of wheels 36 to achieve movement in the Y direction.

[0021] In this way, one or more robotic load handling devices 30 can move around the top surface of the stacks 12 on the frame structure 14 under the control of a central picking system (not shown). Each robotic load handling device 30 is provided with means for lifting out one or more bins or containers from the stack to access the required products. In this way, multiple products can be accessed from multiple locations in the grid and stacks at any one time.

[0022] Figure 4 shows a typical storage system as described above, the system having a plurality of load handling devices 30 active on the stacks 12. In addition, a robotic service device 50 is positioned on the grid 14.

[0023] It will be appreciated that any form of load handling 30 device may be in use and that the robotic service device may be suitably adapted to interact with any such load handling device 30.

[0024] A first form of a second type of robotic service device 50, will now be described with reference to Figures 5 to 7.

[0025] Referring to Figure 5, the robotic service device 50 comprises a vehicle 52 having first and second sets of wheels 54, 56 that are engageable with the first and second sets 22a, 22b of rails 22, respectively.

[0026] The robotic service device 50 is provided with features additional to those of the robotic load handling device 30. As can be seen in Figures 5 and 6, the device 50 is provided with a releasable latching mechanism 58 and camera means 60. Furthermore, the device 50 is provided with cleaning means such as brush mechanisms 62 and a vacuum cleaning system 64 mounted adjacent each set of wheels 54, 56. Moreover, the device 50 includes a spray device 66 capable of discharging suitable detergent under the control of the central picking system (not shown).

[0027] In a similar manner to the operation of the load handling device 30, the first and second sets of wheels 54, 56 of the robotic service device 50 can be moved vertically with respect to the vehicle 52 to engage or disengage the wheels 54, 56 from the corresponding set of rails 22a, 22b. By engaging and driving the appropriate set of wheels 54, 56, the robotic service device 50 can be moved in the X and Y directions in the horizontal plane on the top of the frame structure 14.

[0028] In the event of a failure or malfunction of a robotic load handling device 30a, the robotic service device 50 is moved on the grid 14 to a location adjacent the malfunctioning device 30a. Once adjacent to the malfunctioning device 30a, the camera means 60 of the service device 50 may be used to view the situation from a control position (not shown). If the load handling device 30a requires removal from the grid 14, then the service device 50 may be releasably latched to the malfunctioning load handling device 30a as shown in Figure 8. The service device 50 may then be used to manipulate the malfunctioning device 30a to a location where it can be serviced or removed entirely from the grid 14.

[0029] It will be appreciated that the form of the releasable latching mechanism 58 need not be as shown in Figures 5 to 9 but that any suitable form of releasable latching mechanism may be used. The latching mechanism 58 may connect to a faulty robotic load handler and either lift it clear off the grid, or be able to raise and lower the sets of wheels on the faulty device, so as to be able to push, pull or drag it to a desired location. The latching mechanism 58 may also include a device for causing the faulty unit's gripper mechanism to be retracted from the grid or make any other mechanical or electrical intervention with the robotic load handler 30.

[0030] Furthermore, it will be appreciated that the service device 50 may be provided with sensor means instead of or in addition to camera means 60. For example, the service device 50 may be provided with sensors that allow a system operator to remotely diagnose a fault with a faulty or stationary robotic load handler 30. This may include, but not be limited to, electrical connection means to connect to a port of the robotic load handler 30 to check for or diagnose faults via an installed diagnostic system. This may further include sensors such as ultrasonic detectors, x-ray cameras, or sensors for assessing the telecommunications functions within the load handling device 30.

[0031] Moreover, the service device 60 may comprise reset means, in addition to or instead of the sensors discussed above, to enable the service device 50 to reset the robotic load handling device 30. The reset means may comprise mechanical means such as a remotely operated manipulator device or it may comprise remotely operable electrical reset means. The mechanical manipulator may further be remotely operable to push the load handling device 30 should the diagnosis suggest the load handling device 30 is simply temporarily stuck on a portion of the grid. Alternatively, the mechanical device may act in conjunction with the service device 50 to push the load handling device to an alternative portion of the grid or off the grid completely.

[0032] In another use of the robotic service device 50, the device 50 is used to travel over the grid 14 to establish the condition of the grid 14. For example, over time spillages and dirt may build up on the grid 14. The service device 50 may be provided with a traction measurement system whereby, for example, one or more wheels 56 are driven whilst one or more wheels 54 are braked, in order to establish if there is a spillage and hence loss of traction for the robotic load handlers 30 on the grid 14. The service device 50 may then be deployed on the grid 14 and the camera means 60 used to remotely view the condition of the grid 14. The brush mechanisms 62, the spray detergent, 66 and the vacuum system 64 may then be used as appropriate to clean the grid 14.

[0033] Spillage of products such as oil onto the grid, which makes the grid slippery, may be detected by ordinary robotic load handlers using slip detection on the wheels. It is then important to deal with the issue immediately to prevent oil to be spread over large portions of the grid. The proposed method would use several aspects of the robotic service 50 to deal with the issue. In use, any robotic device experiencing slippage would be stopped. Other robotic devices within a predetermined radius of the potential spillage would also be stopped. The

picking control system may be used to block all potentially affected areas of the grid in software such that no other robotic devices 30, 50 may access the affected area. One or more robotic service devices may then be deployed initially to clean the area around the now stationary robotic devices. The drive mechanism of the deployed service device 50 may then be used to measure traction, to ensure any spillage is properly removed. The robotic service device 50 may then be used to pick up and remove the affected robotic load handling device 30 to a maintenance area, such that the wheels may be cleaned. Further robotic service devices may be deployed to finish cleaning the affected area until there is sufficient traction on all parts of the grid.

[0034] Furthermore, the robotic service device 50 may be provided with means for assessing the mechanical condition of the tracks and the grid. For example, the service device 50 may use sensor or camera means described above to assess the condition of the grid in addition to or separately from assessing the condition of robotic load handling devices 30.

[0035] For example, the robotic service device may be deployed on to the grid during a housekeeping phase to ensure the stability and integrity of the tracks and grid.

[0036] It will be appreciated that the service device 50 may comprise all, one or any combination of the features described above and that it is not essential to the invention for the service device to include all the sensors and features described. Figures 10 and 11 show an embodiment of the invention. Features similar to that described with reference to examples of robotic devices described earlier will be referenced with the same reference numbers.

[0037] Figure 10 shows an alternative form of robotic service device 150. The robotic service device 150 comprises a substantially bridge shaped vehicle 152. Referring to Figures 10 and 11, the robotic service device 150 comprises a vehicle 152 having first and second sets of wheels 154, 156 that are engageable with the first and second sets 22a, 22b of rails 22, respectively. The bridge-shaped vehicle 152 is sized so as to be capable of straddling a load handling device 30. The service device 150 is provided with a releasable latching or hook mechanism 158 deployable from the underside of the bridge portion.

[0038] In use, the first and second sets of wheels 154, 156 of the robotic service device 150 can be moved vertically with respect to the vehicle 152 to engage or disengage the wheels 154, 156 from the corresponding set of rails 22a, 22b. By engaging and driving the appropriate set of wheels 154, 156, the robotic service device 150 can be moved in the X and Y directions in the horizontal plane on the top of the frame structure 14.

[0039] In this manner, the service device 150 may be deployed on the grid 14 and driven to a point whereby it straddles a malfunctioning load handling device 30 such that the latching or hook mechanism 158 may be used to lift the malfunctioning device 30 from the grid 14. The picking control system may then be used to move the service device 150 to a position on the grid 14 where the malfunctioning load handling device 30 may be removed as necessary. It will be appreciated that, although not shown in the drawings, the service device in the second

embodiment may also have the features described with reference to the first embodiment, including but not limited to brush mechanisms 62, vacuum systems 64, spray systems 66, traction measurement systems and camera means 60, all operational in a similar manner to that described above.

[0040] Figure 12 shows the embodiment of the invention. Features similar to that described with reference to examples of robotic devices described earlier will be referenced with the same reference numbers.

[0041] Referring to Figure 12, the robotic service device 250 comprises a vehicle 252 having first and second sets of wheels 254, 256 that are engageable with the first and second sets 22a, 22b of rails 22, of the grid 14 respectively. The u-shaped vehicle 252 is sized so as to be capable of enclosing a load handling device 30. The service device 250 is provided with a releasable latching or hook mechanism 258 deployable from within the u-shaped portion.

[0042] In use, the first and second sets of wheels 254, 256 of the robotic service device 250 can be moved vertically with respect to the vehicle 252 to engage or disengage the wheels 254, 256 from the corresponding set of rails 22a, 22b. By engaging and driving the appropriate set of wheels 254, 256, the robotic service device 250 can be moved in the X and Y directions in the horizontal plane on the top of the grid 14.

[0043] In this manner, the service device 250 may be deployed on the grid 14 and driven to a point whereby it encloses a malfunctioning load handling device 30 such that the latching or hook mechanism 258 may be used to pull, push or otherwise manipulate the malfunctioning device 30. The picking control system may then be used to move the service device 250 to a position on the grid 14 where the malfunctioning load handling device 30 may be removed as necessary. It will be appreciated that, although not shown in the drawings, the service device may also have the features described with reference to examples of robotic devices described earlier, including but not limited to brush mechanisms 62, vacuum systems 64, spray systems 66, traction measurement systems and camera means 60, all operational in a similar manner to that described above.

[0044] It will be appreciated that the latching device need not take the form of a hook but that any suitable latching means may be used. For example the latching means may be magnetic or electro-magnetic. Furthermore, the latching means may be positioned at any point on the service device, indeed a plurality of latching mechanisms may be employed on all sides of the service device such that a load handling device may be approached and latched from any direction on the grid.

[0045] Moreover, the latching mechanism of the service device may interact with the load handling device in any way suitable to remove the load handling device from the grid. There may be electronic communication or mechanical interaction between the service device and the load handling device of any form in order to release the load handling device from the grid.

[0046] Figures 13 to 15 show a further example of a robotic service device 50. Features similar to that described earlier will be referenced with the same numerals.

[0047] In Figure 13, a pair of robotic service devices 450 are shown connected by a suitable member 452. The member 452 allows the separate robotic service devices 450 to act as a single unit. The member 452 is further provided with connecting, latching and lifting means 454, 456.

[0048] The connected robotic service devices 450 are remotely manoeuvred into position such that they occupy grid spaces adjacent an inoperable load handling device 30. From this position the latching means 454 can be lowered or adjusted to connect with a co-operating latching point 456 on the robotic load handling device 30. Once connected, the lifting means 456 is operated to lift the inoperable load handling device 30 clear of the grid and tracks. Once lifted clear, the connected robotic service devices 450 can be remotely instructed to move to a position off the grid to enable recovery of the robotic load handling device.

[0049] Figures 14 and 15 show alternative configurations for the connected robotic service devices 450 and alternative positions of the member 452 and the connecting latching and lifting means 454, 456.

[0050] It will be appreciated that in this example, it is possible to approach and lift robotic load handling devices from any part of the grid, including the very corners or edges or adjacent supporting structures as the robotic service device 450 connects to the load handling device 30 at a top mounted coupling.

[0051] It will be appreciated that the configurations shown in Figures 13 to 15 are just a selection of a number of possible configurations and that the example is not limited to simply these configurations. The connecting, latching and lifting mechanism may be a single mechanism or three separate mechanisms. The connecting and latching mechanisms may comprise mechanical, magnetic or electro-magnetic means or any other suitable means. The lifting means may comprise winch means 458 or any other suitable lifting means.

[0052] Figure 16 shows another example. Features similar to that described with reference to the previous examples of the invention will be referenced with the same reference numbers.

[0053] Referring to Figure 13, the service device 350 comprises a substantially planar vehicle 352 having first and second sets of wheels 354, 356 that are engageable with the first and second sets 22a, 22b of rails 22, of the grid 14 respectively. The planar vehicle 352 is provided with seating means 353 so as to be capable of carrying a user. The service device 350 may be robotically controlled by the picking system control but may also be manually driven by the user (not shown).

[0054] In use, the first and second sets of wheels 354, 356 of the service device 350 can be moved vertically with respect to the vehicle 352 to engage or disengage the wheels 354, 356

from the corresponding set of rails 22a, 22b. By engaging and driving the appropriate set of wheels 354, 356, the service device 350 can be moved in the X and Y directions in the horizontal plane on the top of the grid 14.

[0055] In this manner, the service device 350 may be deployed on the grid 14 and driven to a predetermined point on the grid where inspection or maintenance is required.

[0056] It will be appreciated that, although not shown in the drawings, the service device 350 of the fifth example may also have the features described with reference to the service device in the previous examples, including but not limited to brush mechanisms 62, vacuum systems 64, spray systems 66, traction measurement systems and camera means 60, all operational in a similar manner to that described above.

[0057] In this manner, the integrity of a large robotically controlled picking system can be maintained and cleaned without the requirement of stopping the whole system to retrieve malfunctioning load handling devices or to clean spillages on the grid. In systems of significant size this can represent a substantial decrease in the down time of the system.

[0058] Furthermore, it is possible for the robotic service device described in all or any of the embodiments above to be adapted to carry equipment such as barriers (not shown). The remotely operable mechanical manipulating means may position barriers around a portion of the grid for example, for safety reasons should an operator need to be present on the grid.

[0059] It will be appreciated that robotic service devices as described above may contain one or all of the features described. For example, a service device may be capable of lifting a malfunctioning load handling device off the grid and removing it to a maintenance location on the grid, whilst also comprising traction monitoring means and cleaning devices. Furthermore, a ride-on service device may also be provided with the means to pull a malfunctioning load handling device off the grid.

[0060] Furthermore, the robotic service device 50 may comprise a load carrying portion, similar to the load handling device, the load carrying portion being adapted to carry maintenance and cleaning equipment such as that described above. Moreover, the load carrying portion may be interchangeable such that one service device may be able to perform different functions depending on the load carrying portion provided at any one time.

[0061] It will also be appreciated that the robotic load handling devices 30 may be of the cantilever form shown in Figures 1 to 4, that occupy two grid spacings or alternatively the robotic load handling devices 30 may be of the form shown in Figures 13 to 15 where they occupy only a single grid spacing.

[0062] Many variations and modifications not explicitly described above are also possible without departing from the scope of the invention as defined in the appended claims.

REFERENCES CITED IN THE DESCRIPTION

Cited references

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- [US2701065A \[0004\]](#)
- [EP0767113B \[0005\]](#)
- [EP1037828B1 \[0007\]](#)
- [NO317366 \[0008\]](#)
- [GB1314313A \[0009\]](#)
- [WO2013167907A \[0010\]](#)

PATENTKRAV

1. Øverste niveau af en rammestruktur (14) egnet til et lager eller produktionsmiljø til støtte af robotagtige lasthåndteringsindretninger, hvor det øverste niveau omfatter et første sæt parallelle skinner (22a), der strækker sig i en X-retning og et andet sæt parallelle skinner (22b), der strækker sig i en Y-retning vinkelret på X-retningen, hvor X- og Y-retningerne er i et vandret plan på det øverste niveau af rammestrukturen;

hvor det første og andet sæt skinner (22a, 22b) danner et ensartet gittermønster henover toppen af stakkene, hvilket gittermønster omfatter en række åbninger, hvor hver åbning er en rektangulær åbning og har en bredde i X-retningen og en længde i Y-retningen,

hvor hver skinne i det andet sæt skinner (22b) omfatter en langsgående opdelingsstruktur, der centralt deler den respektive skinne i to tilstødende spor, hvor hvert spor kan gå i indgreb med et hjul af en robotserviceindretning (50),

kendetegnet ved at

hver åbning er omgivet langs sin bredde og længde af en hævet kant tilvejebragt af skinnerne (22a, 22b);

hvor hver skinne i det første sæt skinner (22a) omfatter en langsgående opdelingsstruktur, der centralt deler den respektive skinne i to tilstødende spor, hvor hvert spor kan gå i indgreb med et hjul på en robotserviceindretning (50),

og hvor opdelingsstrukturen af hver skinne i det første set af skinner (22a) omfatter en række hævede opdelere, hvor hver hævet opdeler strækker sig langs og parallelt med den fulde bredde af en tilstødende åbning,

og hvor opdelingsstrukturen af hver skinne i det andet set af skinner (22b) omfatter en række hævede opdelere, hvor hver hævet opdeler strækker sig lang og parallelt med den fulde længde af en tilstødende åbning,

og hvor hver hævet opdeler af opdelingsstrukturen af hver skinne i det første set af skinner (22a) ikke strækker sig længere end bredden af den respektive tilstødende åbning, og hver hævet opdeler af opdelingsstrukturen af hver skinne i det andet sæt af skinner (22b) ikke strækker sig længere end længden af den respektive tilstødende åbning.

DRAWINGS

Drawing

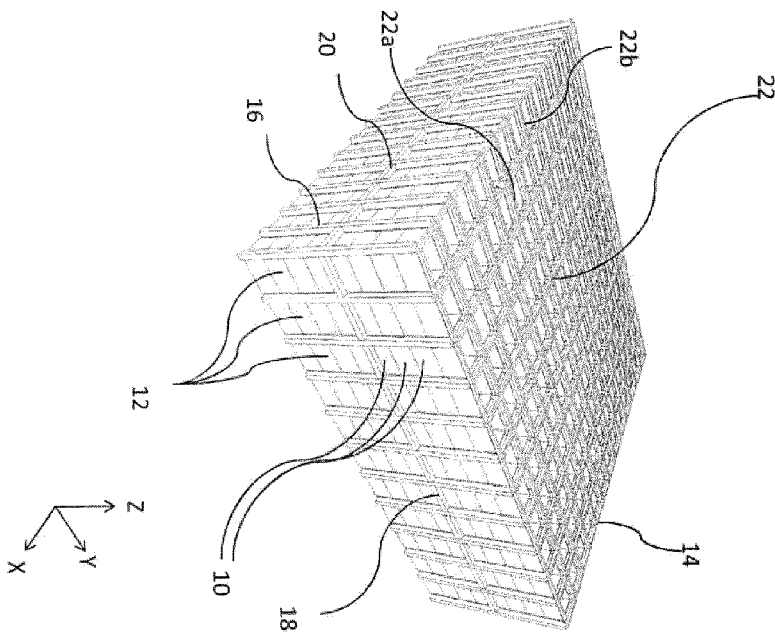


Figure 1

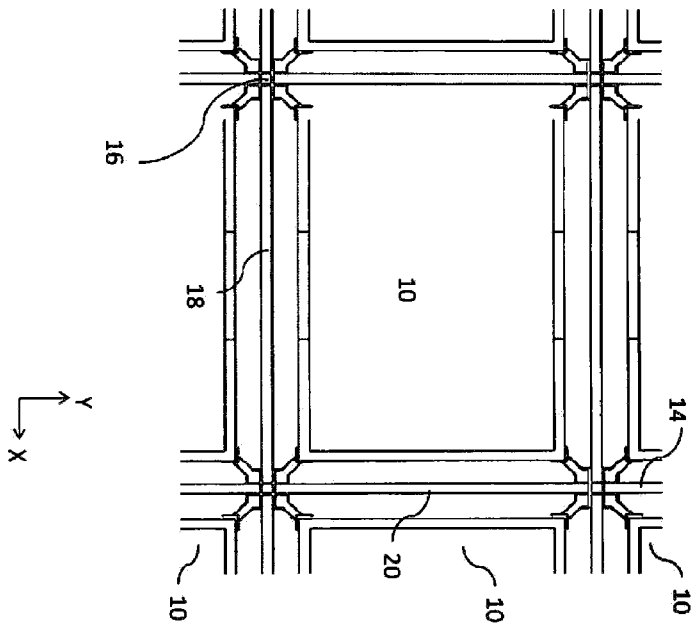


Figure 2

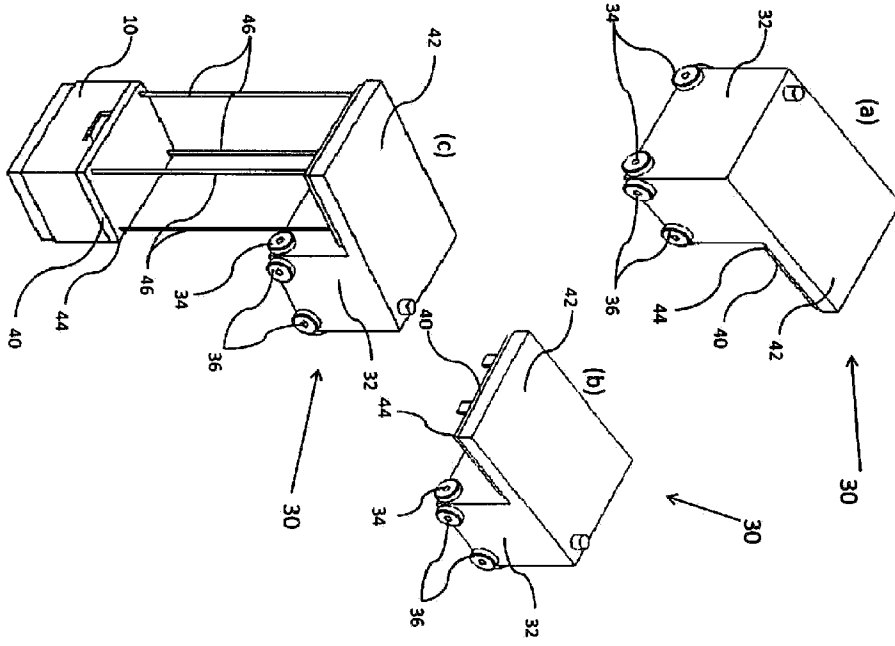


Figure 3

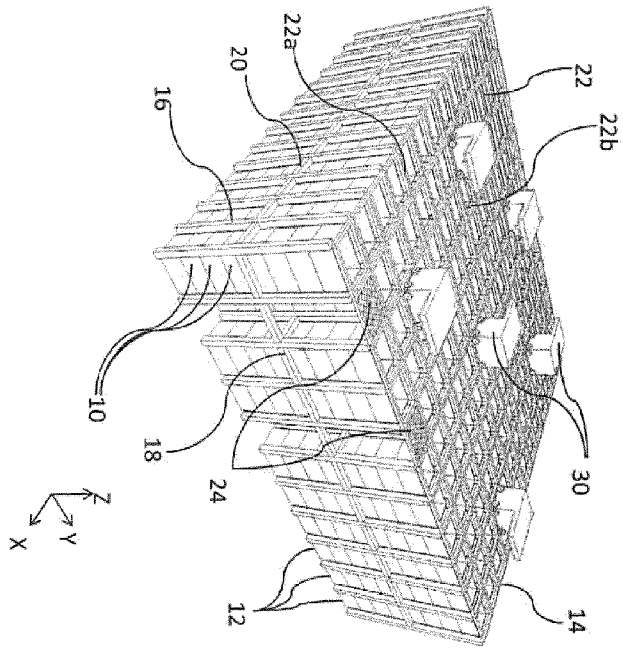


Figure 4

Figure 5

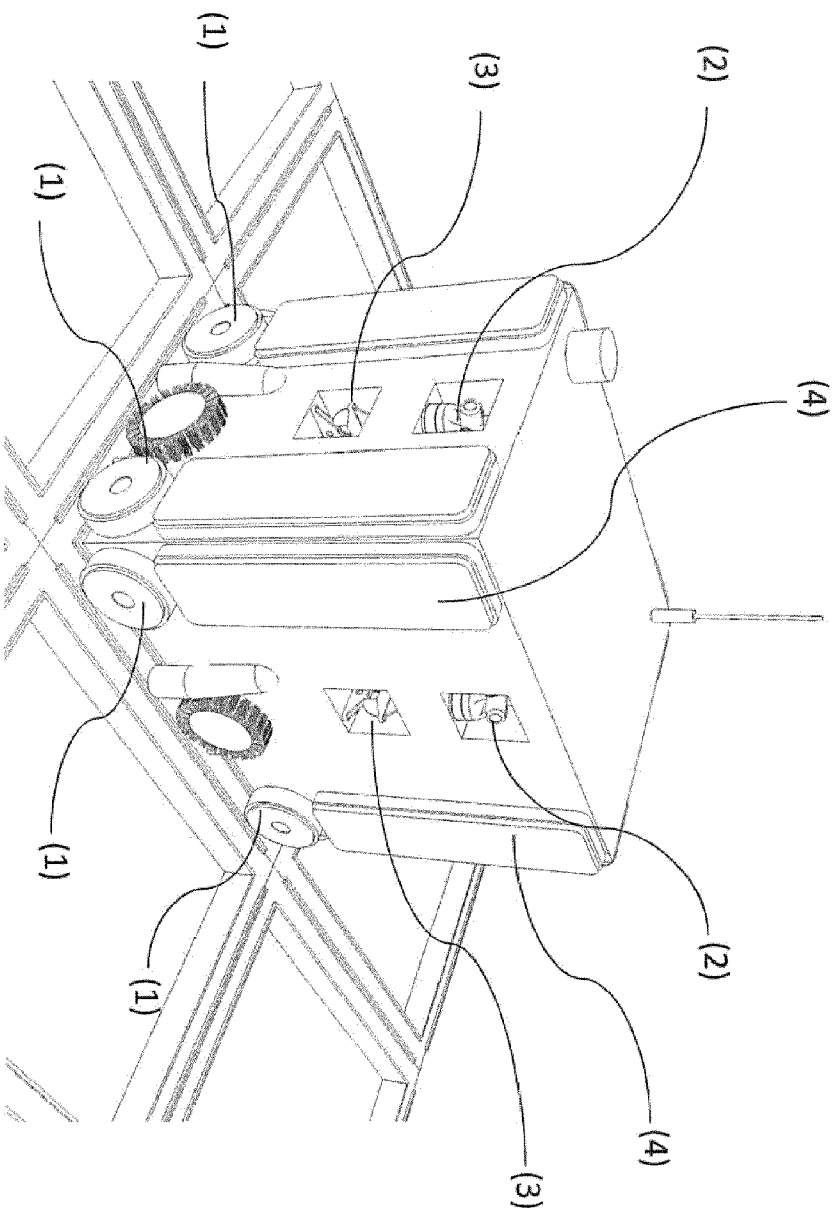


Figure 6

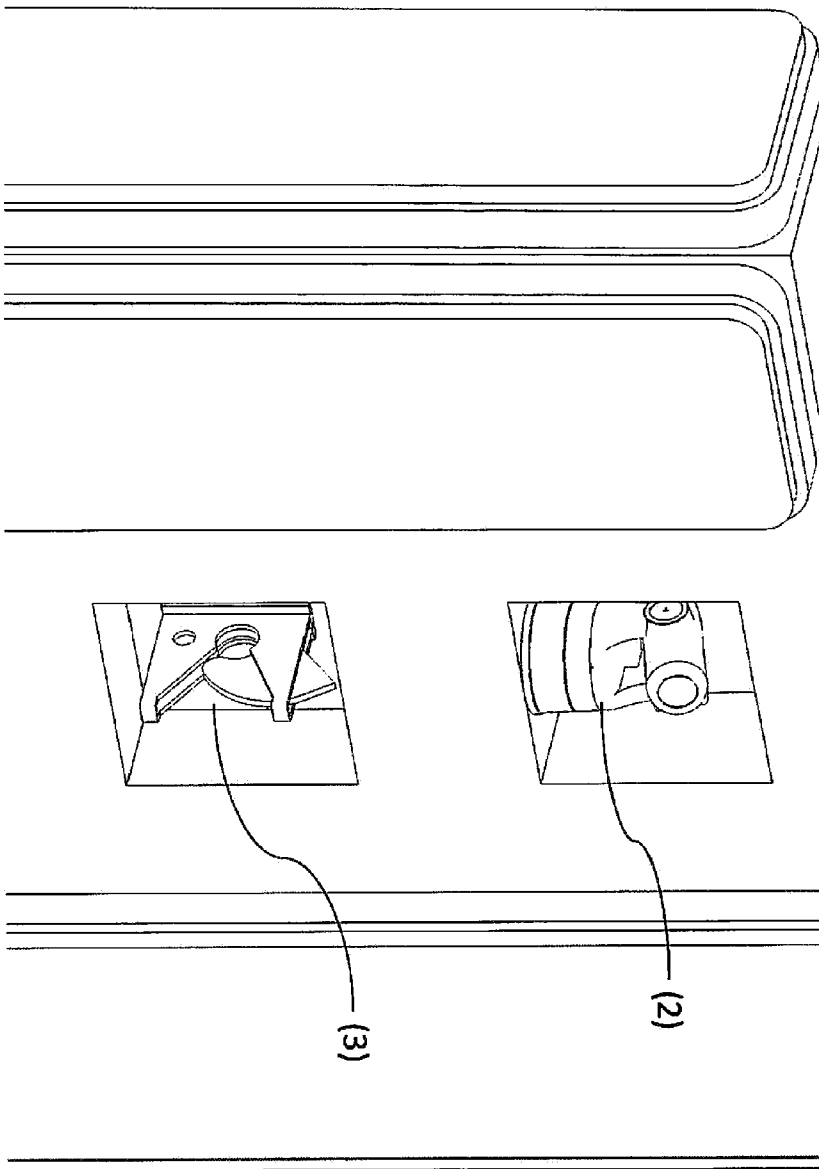


Figure 7b

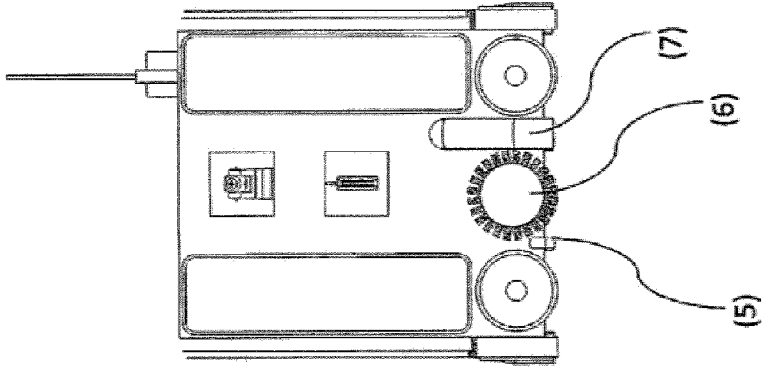


Figure 7a

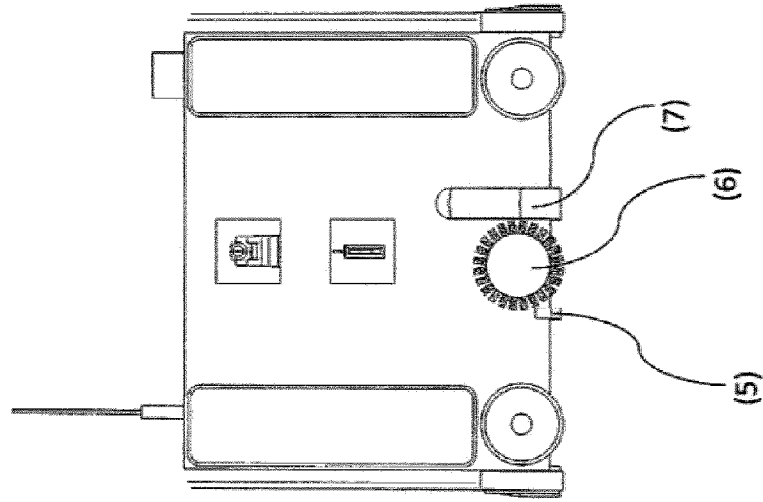


Figure 8

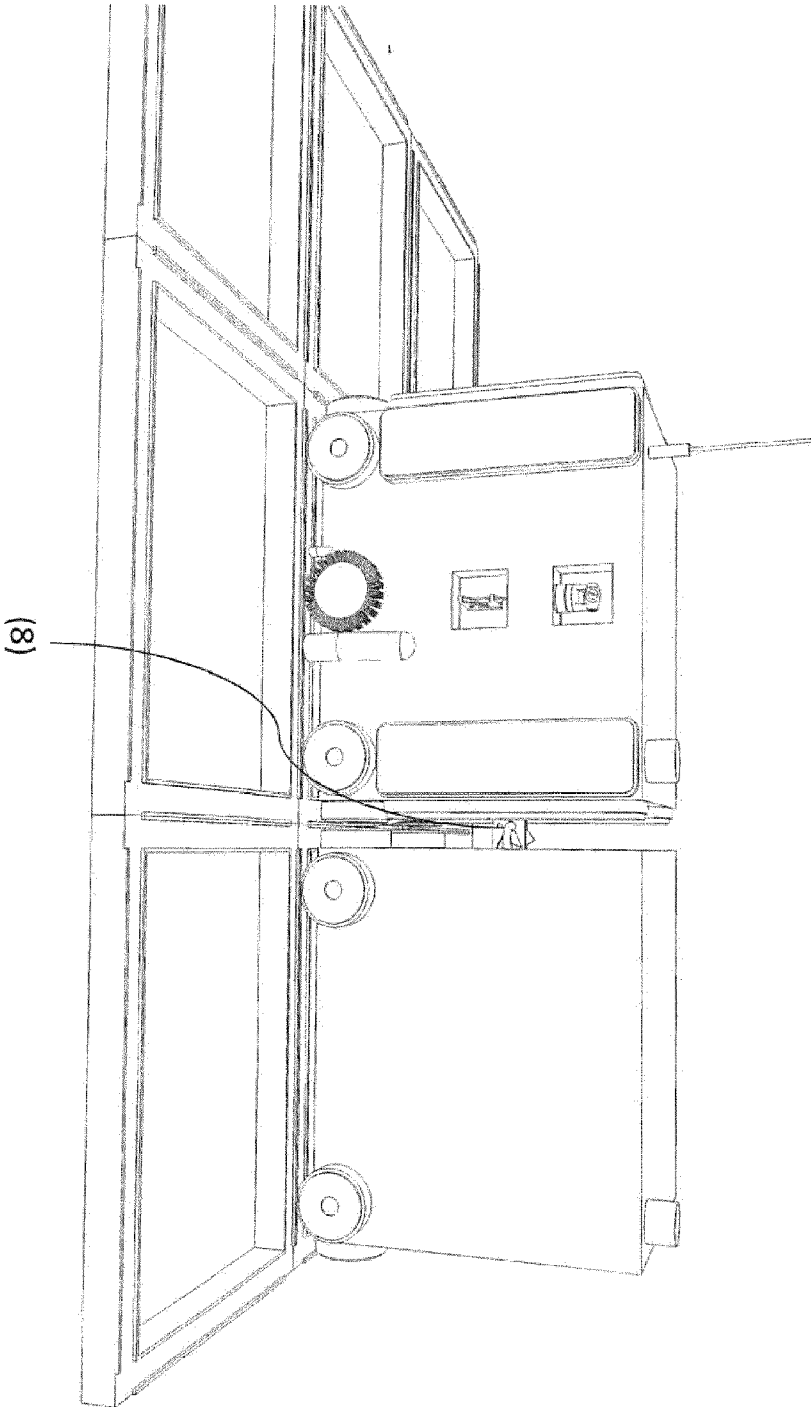


Figure 9

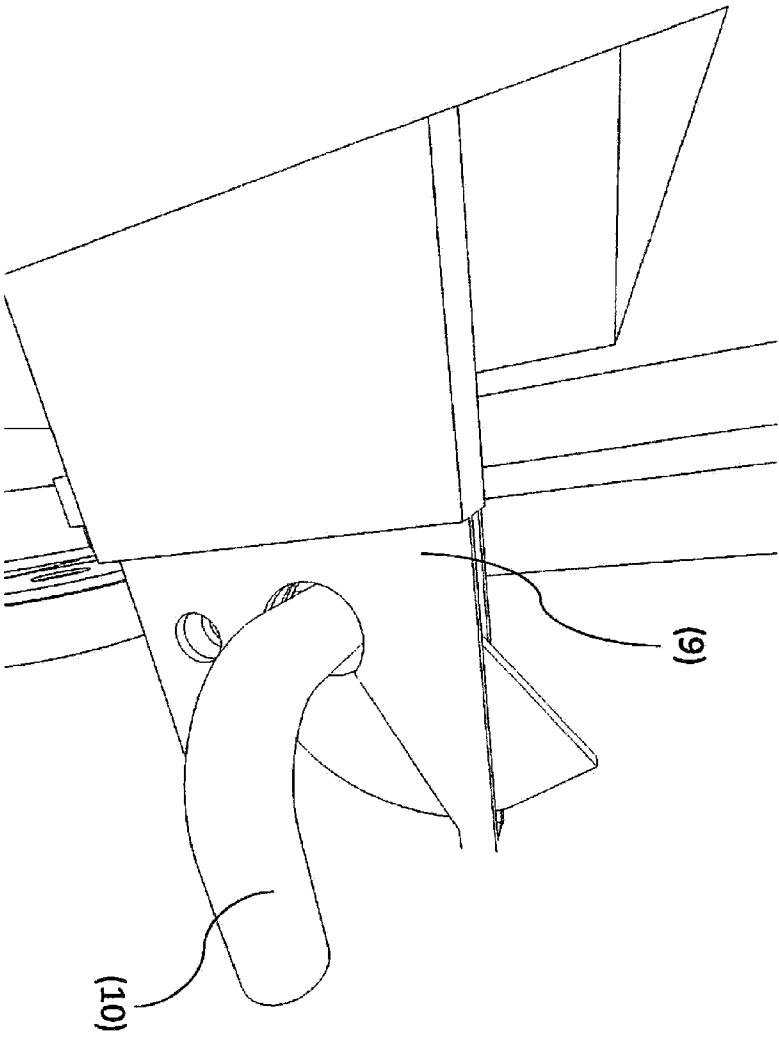


Figure 10

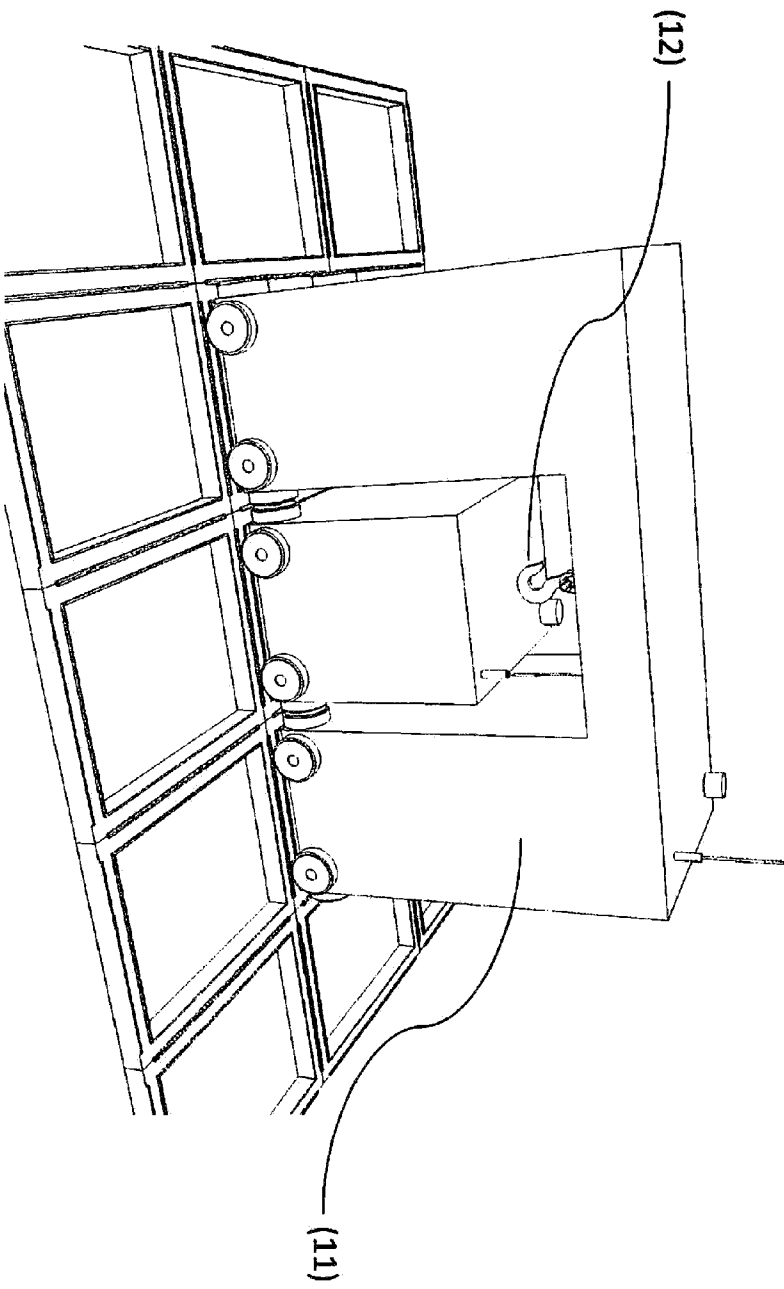


Figure 11

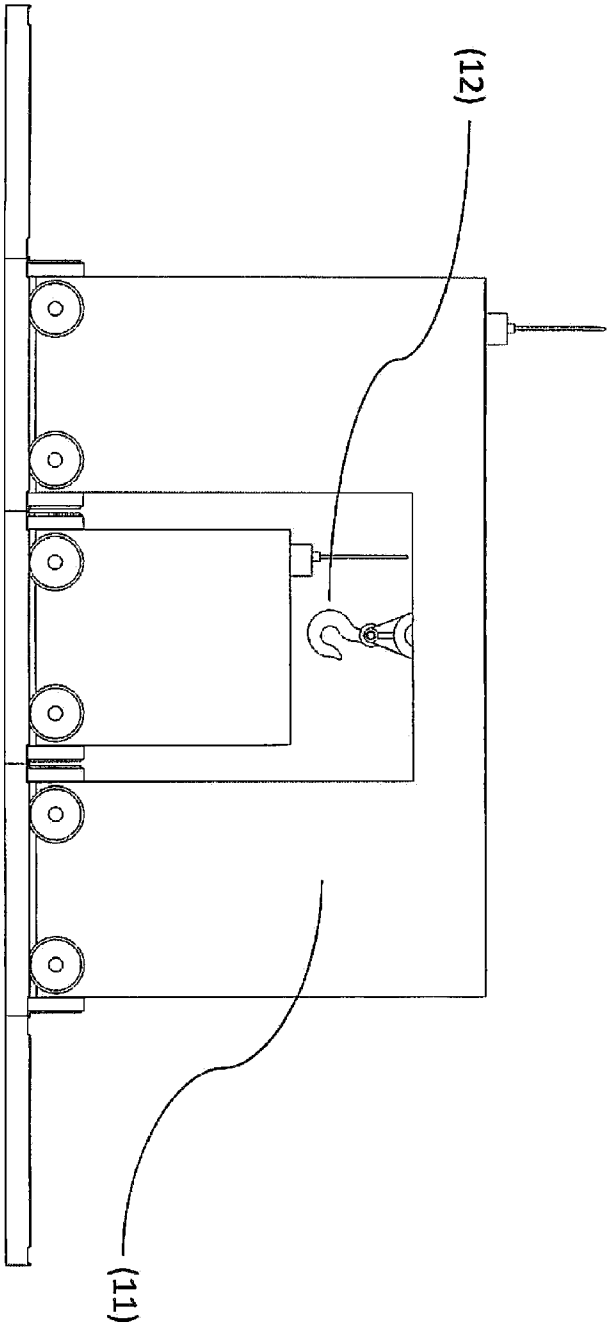
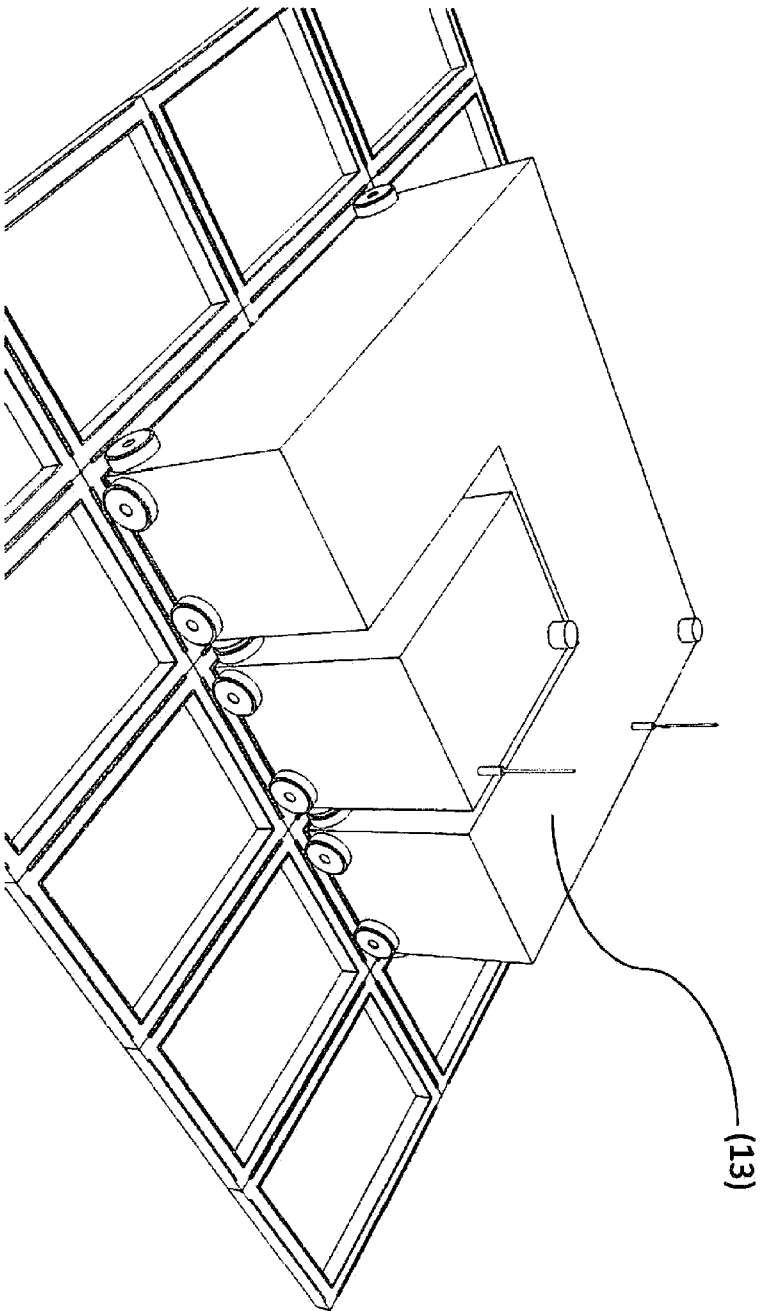
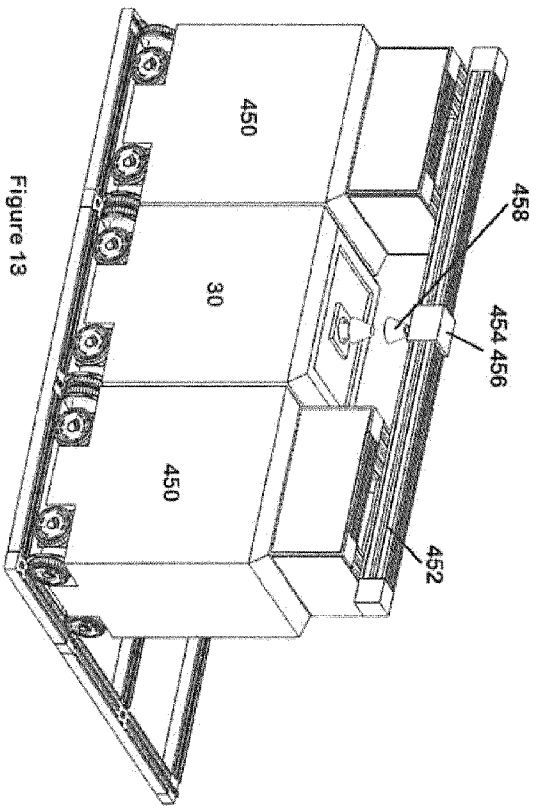


Figure 12





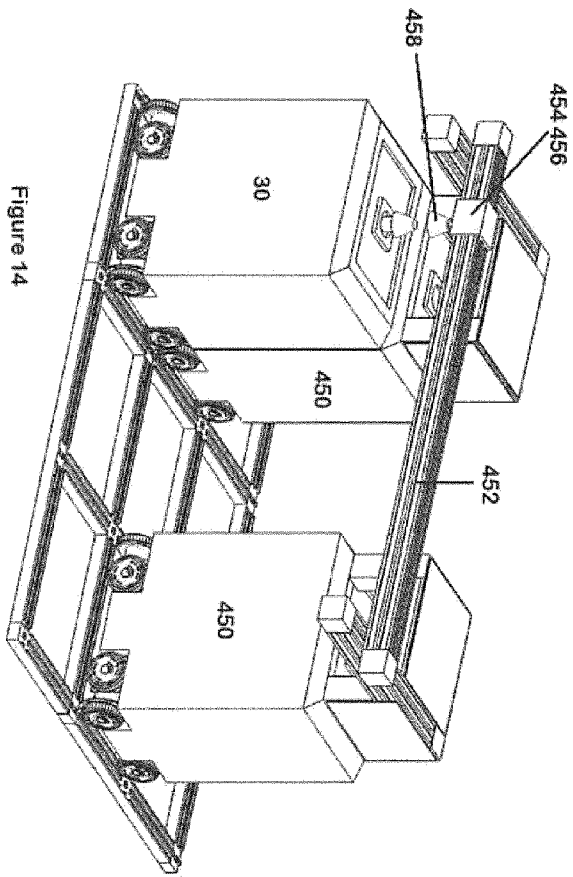


Figure 14

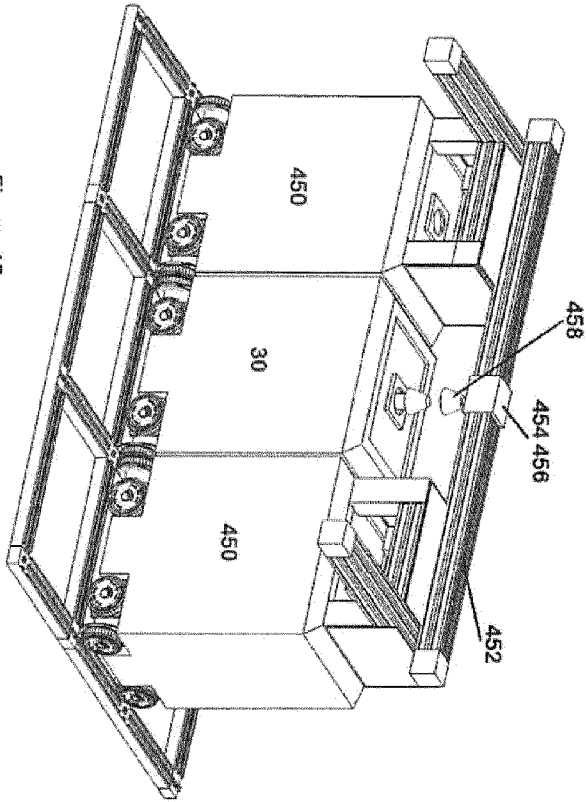


Figure 15

Figure 16

