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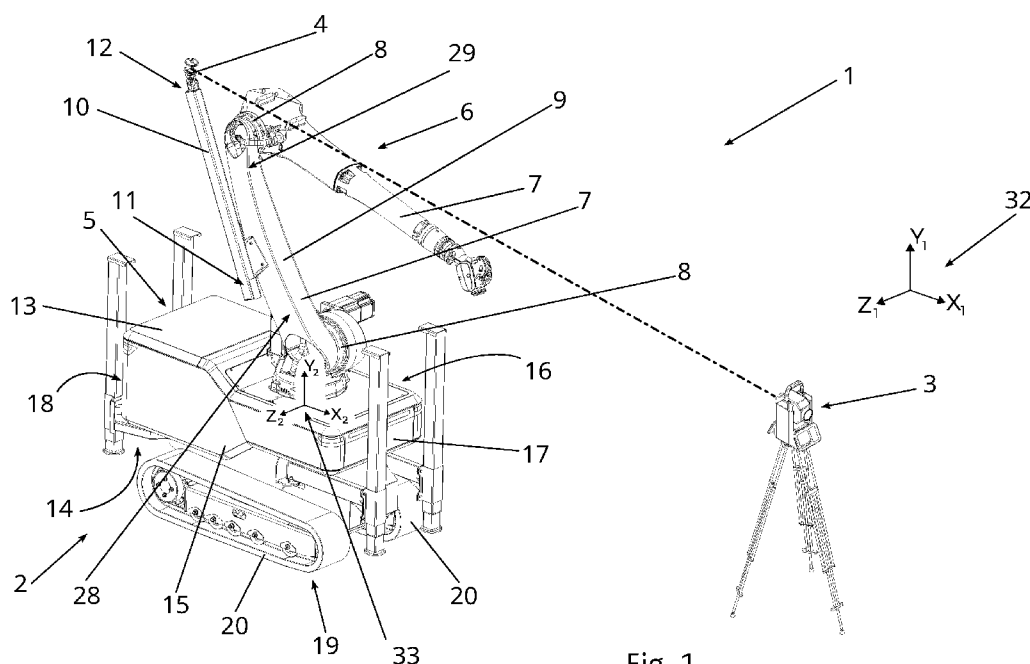


Fig. 1

(57) Abstract: Tracking system (1) for tracking a mobile robot (2), in particular a mobile construction robot at a construction site, comprising: - a tachometer (3) configured to track an optical marker (4); and - a mobile construction robot (2), wherein the mobile construction robot (2) comprises: - a robot base (5); and - a multi-axis robot arm (6) arranged on the robot base (5), wherein the robot arm (6) comprises a plurality of links (7) connected by joints (8), wherein one of the links (7) is configured as a rocker arm (9), wherein the optical marker (4) is mounted on the rocker arm (9) of the robot arm (6), wherein the mobile construction robot (2) is configured to move the rocker arm (9) such that the optical marker (4) is moved to at least a first position, a second position and a third position relative to the robot base (5).

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Tracking System for Tracking a Mobile Robot

The disclosure concerns a tracking system for tracking a mobile robot, in particular a mobile construction robot at a construction site, comprising:

- a tacheometer configured to track an optical marker; and
- a mobile robot, wherein the mobile robot comprises:
 - a robot base; and
 - a multi-axis robot arm arranged on the robot base, wherein the robot arm comprises a plurality of links connected by joints, wherein one of the links is configured as a rocker arm.

Mobile robots are used to automate especially repetitive and physically demanding tasks, for example at construction sites. For example, a mobile construction robot may drill holes at predefined positions or mount anchors. Such mobile construction robots are configured to autonomously move around the construction site, locate the predefined positions at which a specific task is to be performed, and consequently perform the respective task. By means of such a robot, manpower can be deployed more efficiently, and the construction can be sped up drastically.

Typically, such mobile robots comprise a base, a propulsion system for moving the robot, as well as a robot arm with an end effector. The robot arm should comprise of multiple axis so that the robot is able to move the end effector to various positions and orientations with respect to the robot base. The kinematic chain of the robot arm typically comprises a rocker arm, which is pivotably connected to the base, and a boom arm, which is pivotably connected to the rocker arm. Once the construction robot is in the vicinity of a position, where a task is to be completed, the robot moves the robot arm so that by means of the end effector, the respective task can be done.

It is crucial to determine the exact location of the mobile construction robot at the construction site for several reasons. First and foremost, precision is decisive with respect to construction projects. It is necessary to ensure that the location of, for example, the drilled holes are precisely at their intended location to avoid errors and costly delays. In addition,

ensuring the exact location of the drilling can help to provide increased safety on the construction site. Accurate positioning of anchors can help to avoid collisions with other equipment or structures and can also help to prevent injuries to workers. Finally, knowing the exact location of the drilling is also necessary for documentation purposes, as it can provide a clear record of the work that has been completed and the progress of the project. Therefore, both efficiency and as precision are decisive in this context.

Mobile robots are also used for other purposes than construction, where it is essential to know the position of the robot. For example, mobile robots can be used for transportation of goods or cleaning purposes, for example.

Known solutions from the prior art to track robots, in particular mobile construction robots, can be categorized in two groups. Solutions relating to the first group comprise an active optical sensor disposed on a mobile robot in combination with stationary passive elements, such as markers or reflectors, for example at a construction site. In contrast, the second group comprises a passive optical element disposed at the mobile robot and a stationary active optical sensor, such as a total station.

A position-measuring system for measuring the position of a mobile machine tool relating to the first group is for example known from WO 2022 096 337 A1. A mobile machine tool is equipped with a position measuring system, which is configured to measure the position of the mobile machine tool with respect to (passive) markings at the construction site.

A similar method for specifying a position of an instrument head of a robot is known from WO 2021 058 569 A1. The instrument head comprises a distance measuring device with a number of distance measuring sensors. Based on measurements by means of the distance measuring sensors and a known geometry model of the construction site, the position of the instrument head is determined.

A disadvantage of these methods is that rather sensitive optical

sensors need to be deployed at the robot. In case the robot is configured to perform heavy tasks such as drilling, the sensors may be affected by vibrations and contamination by dust. Especially the sensors of WO 2021 058 569 A1 are located directly at the instrument head, which in the context of drilling is subject to particularly severe vibration and dust contamination.

Examples for solutions relating to the second group are known from WO 2016 066 615 A2, CN 113 280 807 A and WO 2020 038 779 A1.

WO 2016 066 615 A2 shows a mobile robotic drilling apparatus for drilling ceilings and walls at a construction site. The apparatus comprises a robotic arm mounted to a substructure. A laser total station is used to measure the position of a reflector prism mounted on the robotic arm.

CN 113 280 807 A shows a mobile robot positioning device. A total station is provided, as well as a fixedly arranged rear-view prism and a station positioning prism. Furthermore, a front-view positioning prism is provided on the mobile robot. The total station determines the position of the front-view positioning prism in relation to the fixed rear-view prism, the station positioning prism and the position of the total station. The front-view positioning prism is mounted at the mobile robot. The system is rather complex, since in addition to the total station and the front-view positioning prism, two further stationary prisms are deployed.

Another mobile construction robot is known from WO 2020 038 779 A1. The mobile construction robot comprises a driving platform and a robotic arm with several arm segments that are interconnected by rotary joints as well as an end-effector. An optical marker is mounted to the end-effector. The end-effector can be moved by controlling the robotic arm. A laser total station is placed on the construction site to track the optical marker. The position of the optical marker relative to the optical tracker is measured in two positions of the end-effector with the optical tracker. The position of the end-effector relative to the driving platform in these two positions is measured by means of rotary sensors mounted on the robotic

arm. The rotary sensors yield the joint angles of the rotary joints. These measurements are used to determine the position and the orientation of the driving platform. However, the measurement of the position of the end-effector relative to the driving platform is prone to a relatively large uncertainty, since individual uncertainties of the rotary sensors add up starting from the driving platform to the end-effector. This uncertainty propagates to the determination of the position and the orientation of the driving platform. In addition, the end-effector and consequently the optical marker is subject to dust contamination, especially in case of drilling.

It is therefore an object of the invention to alleviate or eliminate at least some of the disadvantages of the prior art. In particular, it is an object of the invention to provide a simple and robust method for determining the position and the orientation of a mobile robot, in particular a mobile construction robot at a construction site, with increased precision and accuracy.

This object is solved by a tracking system of the above-mentioned type, wherein the optical marker is mounted on the rocker arm of the robot arm, wherein the mobile robot is configured to move the rocker arm such that the optical marker is moved to at least a first position, a second position and a third position relative to the robot base.

Furthermore, this object is solved by a method for tracking a mobile robot, in particular a mobile construction robot at a construction site, wherein the mobile robot comprises a robot base and a multi-axis robot arm arranged on the robot base, wherein the multi-axis robot arm comprises a plurality of links connected by joints, wherein one of the links is configured as a rocker arm, with the steps of:

- providing a tacheometer, in particular at the construction site, wherein the tacheometer is configured to track an optical marker;
- moving an optical marker mounted on the robot arm of the mobile construction robot to at least a first position, a second position and a third position relative to the robot base by

means of the robot arm;

- tracking the optical marker by means of the tacheometer in at least the first position, the second position and the third position relative to the tacheometer; and
- determining a position and an orientation of the robot base based on the tracked first position, the tracked second position and the tracked third position of the optical marker, wherein the optical marker is mounted on the rocker arm.

Furthermore, the object of the invention is solved by a mobile robot, in particular a mobile construction robot, comprising:

- a robot base; and
- a multi-axis robot arm arranged on the robot base, wherein the robot arm comprises a plurality of links connected by joints, wherein one of the links is configured as a rocker arm,
 - an optical marker mounted on the robot arm, the optical marker being arranged for tracking with a tacheometer, wherein the optical marker is mounted on the rocker arm of the robot arm, wherein the mobile robot is configured to move the rocker arm such that the optical marker is moved to at least a first position, a second position and a third position relative to the robot base.

The mobile robot may be a mobile construction robot. The mobile construction robot as well as the tracking system may, for example, be deployed at a construction site for a building structure, which, for example, may be a building, a tunnel, a road, a bridge, a car park, a hospital, or any other infrastructure project where many, for example, several hundred or more, repetitive tasks such as drilling holes or mounting anchors are required.

The tracking system comprises a tacheometer, configured to track an optical marker. The tacheometer may be a laser total station. The tacheometer is provided and placed at a site where the mobile robot is deployed, in particular at a position where the tacheometer has a broad overview of the site. The tacheometer may be configured to automatically track the optical marker. Tracking includes measuring a distance between the tacheometer and the optical marker, as well as measuring a polar angle and

an azimuthal angle of a line of sight in between the tacheometer and the optical marker with respect to a reference coordinate system. The optical marker may be tracked either in a stationary position or, alternatively, while moving. The tacheometer may comprise a source of electromagnetic radiation, in particular visible light. For example, the tacheometer may comprise an LED or a laser. The optical marker may be a reflector or a prism, for example. The optical marker may be a purely passive element. The optical marker may reflect at least a portion of electromagnetic radiation emitted by the tacheometer and incident on the optical marker to the tacheometer. The position of the tacheometer may be used to define a global reference coordinate system within the construction site. The position of the tacheometer with respect to the site, e.g., the construction site, is known. For example, the position of the tacheometer may be fixed and measured during or after placing the tacheometer.

The mobile robot, which is to be tracked, has a robot base, which may have a chassis for a propulsion system and a robot base body on top of the chassis. The robot base may be generally box-shaped. The robot base may, for example, house electronics, control equipment, pneumatic and/or hydraulic compressors. The robot base may have a top side, a lower side, a first lateral side, a second lateral side, a first end side and a second end side. A propulsion system is arranged on the lower side of the robot base, such that at least a part of the propulsion system is in contact with a surface, such as a ground, of for example, the construction site in order to move the mobile robot. The propulsion system may, for example, comprise a motor, wheels and/or a continuous track. The top side of the robot base is opposite of the lower side of the robot base. The propulsion system may have a main axis of propulsion. The first lateral side and the second lateral side may extend essentially upwards and parallel to the main axis of propulsion, whereas the first end side and the second end side may be essentially orthogonal to the main axis of propulsion (i.e., the direction of movement going straight forward or backward). The mobile robot further comprises a multi-axis robot arm with an end effector. The multi-axis robot arm may be arranged on the top side of the robot base, for example.

For the purpose of this disclosure, all directions and positions, such as "vertical", "horizontal", "upper and lower region" are given with respect to the intended use of the mobile robot on a horizontal underground. Of course, the mobile robot may drive on an inclined surface. In this case, the directions and positions must be transferred accordingly.

The robot arm comprises a kinematic chain with multiple links connected via joints. The kinematic chain comprises a distal chain end and a proximal chain end with respect to the robot base. The proximal chain end is connected to the robot base, whereas the distal chain end may comprise an end effector. The end effector may, for example, comprise a holder for releasably mounting an anchor mounting tool and/or a drill bit for producing drilling holes at a construction site. Each joint of the kinematic chain may connect at least two links so that the connected links can pivot or rotate relative to each. The links therefore can be moved with respect to the robot base. One of the links is configured as a rocker arm. The rocker arm may be the first link of the kinematic chain (starting from the proximal chain end) that can be pivoted about a horizontal axis with respect to the robot base. The rocker arm is elongated in a direction transverse to the axis about which the rocker arm is pivotable with respect to the robot base. The rocker arm may be the first link of the kinematic chain, which can be moved around an axis that does not coincide with a main axis of extension of the respective link. In particular, the rocker arm may be the first link of the kinematic chain, which is pivotable around an axis that is essentially orthogonal to the main axis of extension of the respective link. Therefore, the rocker arm is the first link, which may travel upwards or downwards with respect to the robot base. The robot arm may comprise six axes, in order to be able to move the end effector in various positions with various orientations with respect to the robot base. The link following the rocker arm in proximal direction of the robot arm (with respect to the robot base) may be configured as a boom arm. The boom arm may be pivotable with respect to the rocker arm. The end effector may be connected to the boom arm. An exemplary robot arm with a rocker arm and a boom arm is shown in

US 9 950 423 B2.

The mobile robot comprises means to determine the positions of the axis of the robot arm, i.e., the (angular) positions of the joints. In particular, the mobile robot may comprise rotary sensors to determine the angular positions of the joints. Since the geometry of the links and joints is known, the (angular) positions of the joints are sufficient to calculate the position and orientation of each of the links of the robot arm with respect to the robot base.

The optical marker is mounted on the rocker arm of the robot arm for tracking with the tacheometer. The optical marker is immovably connected to the rocker arm such that the optical marker follows the movement of the rocker arm, i.e., the relative location of the optical marker with respect to the rocker arm is fixed regardless of the relative position of the rocker arm with respect to the robot base. The mobile robot is configured to move the rocker arm such that the optical marker is moved to at least a first position, a second position and a third position relative to the robot base. These at least three measurement positions establish a minimum number of necessary tracked positions; however, the optical marker may be continuously tracked (i.e., at a large number of positions), and additional measurement positions are therefore preferable for corresponding increases in accuracy. For example, the optical marker may be tracked by the tacheometer in at least five positions, preferably in at least 20 positions, more preferably in at least 100 positions. The mobile robot may respectively be configured to move the rocker arm such that the optical marker is moved to at least five positions, preferably at least 20 positions, more preferably at least 100 positions, relative to the robot base. The position of the robot base with respect to the tacheometer remains constant while the optical marker is moved to the first position, the second position and the third position. There is a direct line of sight between the tacheometer and the optical marker in the first position, the second position and the third position. The tacheometer is configured to track the optical marker in at least the first position, the second position and the third position relative to the tacheometer, i.e., the

tacheometer determines a distance between the optical marker and the tacheometer as well as the polar angle and the azimuthal angle between the optical tracker and the tacheometer with respect to the global coordinate system. The tacheometer may be at the origin of the global coordinate system. The measurement yields a first distance d_1 between the tacheometer and the optical marker in the first position, a second distance d_2 between the tacheometer and the optical marker in the second position, and a third distance d_3 between the tacheometer and the optical marker in the third position. Accordingly, the measurement yields a first polar angle φ_1 , a first azimuthal angle θ_1 , a second polar angle φ_2 , a second azimuthal angle θ_2 , a third polar angle φ_3 , and a third azimuthal angle θ_3 .

The position and the orientation of the robot base is determined based on the tracked first position, the tracked second position and the tracked third position of the optical marker. The determination of the robot base is based on the measured distances d_1 , d_2 and d_3 , as well as the angles φ_1 , φ_2 , φ_3 , θ_1 , θ_2 , and θ_3 . In addition, the positions of the axes, i.e., the positions of the relevant joints in between the robot base and the rocker arm are known. Also, the (fixed) position of the optical marker on the rocker arm is known. These measurements and the known additional information are used to determine the position and orientation of the robot base with respect to the tacheometer. The position of the robot base with respect to the tacheometer may relate to the coordinates of a reference point of the robot base. For example, a center of gravity of the robot base may be the reference point. Alternatively, a point at a surface of the robot base may be the reference point. The orientation of the robot base may relate to an orientation of the robot base within the global coordinate system. For example, the mobile robot may comprise a main axis of propulsion (i.e., the direction of movement going straight forward or backward). There may be an orientation vector parallel to the main axis of propulsion, which starts at the second end side of the robot base and ends at the first end side of the robot base, i.e., the orientation vector points in forward direction with respect to the propulsion. The orientation of the orientation vector within the global coordinate system may relate to the orientation of the robot base. The

orientation of the robot base may be defined in various ways, it is however crucial to have a relationship between local coordinates of the robot arm, i.e., the positions of the joints, and the global coordinate system. In general, the robot base has six degrees of freedom in the three-dimensional space. Namely three translational degrees of freedom and three rotational degrees of freedom. The translational degrees of freedom relate to the position of the mobile robot, whereas the rotational degrees of freedom relate to the orientation of the mobile robot. The position and orientation of the robot base are determined relative to the position of the tacheometer in the global coordinate system. Consequently, a movement of the robot arm relative to the robot base can be measured internally by the robot, whereas due to the determined position and orientation of the robot base, the movement of the arm is known in terms of the global coordinate system.

Since the rocker arm may be the first link that can be pivoted about a horizontal axis, the rocker arm comprises a minimum of one degree of freedom of movement with respect to the robot base. On the other hand, the rocker arm has fewer degrees of freedom as compared to further links distal of the rocker arm. Therefore, the position and orientation of the rocker arm with respect to the boom arm is known with greater certainty, i.e., less uncertainty, than the position and orientation of further links of the robot arm distal of the rocker arm. The rocker arm is also the first link of the robot arm proximal of the robot base that can be moved upwards or downwards to lift the end effector. For example, the rocker arm may comprise a length of 100 mm to 4000 mm, preferably 500 mm to 2000 mm, and/or may be pivotable by an angle in a range of 10° to 360° .

In order to determine the position and orientation of the robot base with high accuracy and precision, the position of the optical marker with respect to the robot base needs to be known with as little uncertainty as possible. Arranging the optical marker at the rocker arm allows to determine the position of the optical marker with particularly low uncertainty. Only the uncertainties of joint positions of those joints in between the

rocker arm and the robot base are relevant for the uncertainty of position of the optical marker.

In addition, the accuracy and precision are also influenced by the distances between the first position, the second position and the third position of the optical marker respectively. The tacheometer yields measurements with uncertainties Δd for the measured distances, $\Delta \varphi$ for the measured polar angles and $\Delta \theta$ for the measured azimuthal angles. Mainly due to these uncertainties, a greater distance between the first position, the second position and the third position is beneficial, so that the relative uncertainty of the determined position of the robot base is low. Arranging the optical marker at the rocker arm is also in this aspect beneficial, as it enables the mobile robot to move the optical tracker significantly with respect to the robot base.

The tracking system may comprise a processor, configured to determine the position and the orientation of the robot base, based on at least the tracked first position, the tracked second position and the tracked third position. The processor may be within the mobile robot. Alternatively, the processor may be within the tacheometer. Optionally, the processor may be part of an external computer. The processor may be connected to both the tacheometer and the mobile robot, in particular to the rotary sensors of the tacheometer, for example, via GSM, and may be configured to receive data and to send data. The processor may be configured to control the tacheometer and/or the mobile robot. The processor may have access to a computer-readable medium, such as electronic storage.

The computer readable medium may store an electronic copy of a plan of the site, wherein the plan may indicate the positions at which the mobile robot should perform a task. The processor may be configured to control the movement of the mobile robot accordingly.

Optionally, the multi-axis robot arm may comprise at least a first link and a second link, wherein the first link is connected to the robot base via a first joint, wherein the second

link is connected to the first link via a second joint, wherein the second link is configured as the rocker arm. This way, the rocker arm comprises more than one degree of freedom of movement.

Optionally, the first joint provides a first degree of freedom of movement, wherein the second joint provides a second degree of freedom of movement, such that the movement of the rocker arm with respect to the robot base has the first degree of freedom and the second degree of freedom. The first link of the robot arm may be configured as a rotating table. The rotating table may be connected to the robot base such that the robot arm can be rotated around a vertical axis with respect to the robot base. A main axis of extension of the rotating table may coincide with an axis of rotation, around which the rotating table can be rotated. The first degree of freedom then is related to a rotation around a vertical axis, whereas the second degree of freedom is related to a rotation around the axis around which the rotating table can rotate. A second degree of freedom of the rocker arm allows the mobile robot to move the optical tracker in a greater variety of positions. In contrast, the end effector may have six degrees of freedom with respect to the robot base.

For example, the rocker arm may comprise a distal end and a proximal end relative to the robot base, wherein the optical marker is arranged at the distal end of the rocker arm. Due to the length of the rocker arm, the distal end of the rocker arm has a greater travel than the proximal end when the rocker arm is pivoted with respect to the robot base. Therefore, greater distances between the first position, the second position and the third position can be achieved. This leads to a lower uncertainty of the determined position and orientation of the robot base. In addition, the distal end of the rocker arm is, in typical use, among the most elevated elements of the mobile robot. Therefore, there may be a direct line of sight between the optical marker and the tacheometer mostly independent from the orientation of the robot base with respect to the tacheometer.

Optionally, the optical marker is mounted on the rocker arm via an elongated member. The elongated member is immovably connected

to the rocker arm, i.e., the relative location of the rocker arm with respect to the elongated member is fixed. The elongated member may improve the visibility of the optical marker. For example, the elongated member may be arranged such that the line of sight between the tacheometer and the optical marker is unobstructed by the rocker arm in most cases. The elongated member may be arranged such that links of the robot arm proximal of the rocker arm cannot touch the elongated member, regardless of the angular position of the joints.

The elongated member may comprise a proximal end and a distal end with respect to the robot base, wherein the optical marker is arranged at the distal end of the elongated member. Due to the length of the elongated member, the distal end of the elongated member has a greater travel than the proximal end when the rocker arm (and therefore also the elongated member) is pivoted with respect to the robot base. Therefore, greater distances between the first position, the second position and the third position can be achieved. This leads to a lower uncertainty of the determined position and orientation of the robot base.

For example, the elongated member may be arranged essentially parallel to the rocker arm. The elongated member comprises a main axis and the rocker arm comprises a main axis. The main axis of the elongated member may be essentially parallel to the main axis of the rocker arm.

The distal end of the elongated member may extend beyond the distal end of the rocker arm. The rocker arm comprises a main axis, wherein the elongated member is arranged such that the distal end of the elongated member is further away from the proximal end of the rocker arm than the distal end of the rocker arm is with respect to the main axis of the rocker arm. The distal end of the elongated member may be easily placed at an elevated position of the mobile robot. Therefore, there may be a direct line of sight between the optical marker and the tacheometer mostly independent from the orientation of the robot base with respect to the tacheometer. Specifically, the line of sight is not or at least less obstructed by the rocker arm in this arrangement.

Optionally, the elongated member may comprise a main part and an end part, wherein the end part is connected to the main part via an adjustable swivel joint, wherein the optical marker is arranged on the end part. The adjustable swivel joint may be used to adjust an angle and/or a relative position of the optical marker with respect to the main part. The adjustable swivel joint may be used to improve the visibility of the optical marker depending on the tasks and/or the environment of the mobile robot. The adjustable swivel joint is not manipulated in normal use of the mobile robot, e.g., while the mobile robot performs tasks. The adjustable swivel joint may be adjusted manually, for example, before the mobile robot is deployed. The adjustable swivel joint may comprise a fastener to fix the location of the end part with respect to the main part. The fastener is in a fixed position in normal use of the mobile robot.

By way of example, the disclosure is further explained with respect to some selected embodiments shown in the drawings for purposes of illustration. However, these embodiments shall not be considered limiting for the disclosure.

Fig. 1 shows a schematic illustration of a tracking system for tracking a mobile construction robot with a tacheometer and a mobile construction robot.

Fig. 2 shows a robot arm with a rocker arm and an optical marker attached to the rocker arm.

Fig. 1 shows a tracking system 1 for tracking a mobile robot 2. The tracking system comprises a tacheometer 3, in this case a laser total station, configured to track an optical marker 4. Furthermore, the tracking system 1 comprises the mobile robot 2, which is in this example configured as a mobile construction robot. The mobile robot 2 comprises a robot base 5 and a multi-axis robot arm 6 mounted on the robot base 5. The robot arm 6 comprises a plurality of links 7 connected by joints 8 (see fig. 2 for details). One of the links 7 is configured as a rocker arm 9. The optical marker 4 is mounted on the rocker arm 9 of the robot arm 6. The mobile construction robot 2 is configured to move the rocker arm 9 such that the optical marker 4 is moved to

at least a first position, a second position and a third position relative to the robot base 5. The optical marker 4 is arranged for tracking with the tacheometer 3.

The optical marker is mounted on the rocker arm via an elongated member 10. The elongated member 10 comprises a proximal end 11 and a distal end 12 with respect to the robot base 5, wherein the optical marker 4 is arranged at the distal end 12 of the elongated member 10. The elongated member 10 is arranged essentially parallel to the rocker arm 9. The elongated member 10 has a main axis of extension and the rocker arm 9 has a main axis of extension, which axis are essentially parallel to each other.

The rocker arm 9 comprises a proximal end 28 and a distal end 29 relative to the robot base 5. The distal end of the elongated member 12 extends beyond the distal end 29 of the rocker arm 9.

The elongated member 10 is arranged such that the distal end of the elongated member 12 is further distant from the proximal end 28 of the rocker arm 9 than the distal end 29 of the rocker arm 9 is with respect to the main axis of the rocker arm 9. The distal end of the elongated member 12 is in this case in typical use among the most elevated elements of the mobile robot 2, as can also be seen in fig. 1. There is a direct line of sight between the tacheometer 3 and the optical marker 4.

The method for tracking the mobile robot 2, in this example a mobile construction robot at a construction site, comprises the steps:

- providing the tacheometer 3 (in this example at the construction site), wherein the tacheometer 3 is configured to track the optical marker 4;

- moving the optical marker 4 mounted on the robot arm 6 of the mobile robot 2 to at least the first position, the second position and the third position relative to the robot base 5 by means of the robot arm 6;

- tracking the optical marker 4 by means of the tacheometer 3 in at least the first position, the second position and the third position relative to the tacheometer 3; and

- determining a position and an orientation of the robot base 5 based on the tracked first position, the tracked second

position and the tracked third position of the optical marker 4. The optical marker 4 is mounted on the rocker arm 9.

The robot base 5 of the mobile construction robot 2 has a top side 13, a lower side 14 opposite of the top side 13, a first lateral side 15 and a second lateral side 16, a first end side 17, here the front end, and a second end side 18, here the rear end. On the lower side 14 of the robot base 5 a propulsion system 19 is arranged for moving the mobile construction robot 2 on a surface of the construction site. In this example, the propulsion system 19 includes two continuous tracks 20. However, the propulsion system 19 may alternatively comprise wheels (not shown). The multi-axis robot arm 6 is arranged on the top side 13 of the robot base 5. Alternatively, the robot arm 6 may be arranged adjacent to the first end side 17, for example.

For example, in order to drill holes at the construction site, the robot arm 6 may be equipped with an end effector (not shown) configured to drill holes. The robot arm 6 is shown in fig. 2 in greater detail.

The tacheometer 3 is in the origin of a global coordinate system 32 with local (cartesian) coordinates X_1 , Y_1 , and Z_1 . The mobile robot 2 additionally uses a local coordinate system 33 with local (cartesian) coordinates X_2 , Y_2 , and Z_2 . The tracking system is used to find the position and orientation of the robot base 5 within the global coordinate system 32. In other words, the tracking system is used to find a relation between the local coordinate system 33 of the mobile robot 2 to the global coordinate system 32.

Fig. 2 shows the robot arm 6 of fig. 1 in greater detail. The robot arm 6 comprises six links 7 connected by joints 8. The joints 8 enable a movement of two connected links 7 relative to each other. The possible movements of the links 7 relative to each other are indicated by "A", "B", "C", "D", "E" and "F". The robot arm 6 comprises a first link 21 and a second link 22, wherein the first link 21 is connected to the robot base 5 (see fig. 1) via a first joint 23, wherein the second link 22 is connected to the first link 21 via a second joint 24. The second

link 22 is configured as the rocker arm 9. The first link 21 can be connected to the robot base 5, in particular to a chassis or to the top side 13 of the robot base 5. The first link 21 is configured as a rotating table 25. The rotating table 25 can rotate as indicated by "A" around a vertical first axis (not indicated). The rocker arm 9 is pivotably connected to the rotating table 25 and can pivot with respect to the rotating table 25 as indicated by B about a horizontal second axis (not indicated). The first axis and the second axis are essentially perpendicular to one another.

The rocker arm 9 is elongated compared to the rotating table 25. The first axis of rotation of the first link 21, i.e., the rotating table 25, essentially coincides with the main extension axis of the first link 21. In contrast, the second axis is essentially perpendicular to a main extension axis of the rocker arm 9.

The optical marker 4 is mounted on the rocker arm 9 via the elongated member 10. Alternatively, the optical marker may be mounted directly on the rocker arm 9. The elongated member 10 comprises a main part 26 and an end part 27, wherein the end part 27 is connected to the main part 26 via an adjustable swivel joint 30. The optical marker 4 is arranged on the end part 27. The adjustable swivel joint 30 can be used to adjust an angle and/or a relative position of the optical marker 4 with respect to the main part 26. The adjustable swivel joint 30 comprises a fastener 31 to fix the location of the end part 27 with respect to the main part 26. The fastener 31 is in a fixed position in normal use of the mobile robot 2.

When the rocker arm 9 is pivoted around the second axis by means of the second as indicated by "B", the travel of the optical marker 4 is relatively high compared to other parts of the rocker arm 9, in particular compared to the proximal end 28 of the rocker arm 9, for example.

The first joint 23 provides a first degree of freedom of movement (indicated by "A"), wherein the second joint 24 provides a second degree of freedom of movement (indicated by "B"), such

that the movement of the rocker arm 9 with respect to the robot base 5 has the first degree of freedom ("A") and the second degree of freedom ("B").

In the example of figs. 1 and 2, the optical marker 4 moves (along a circular arc) up and down when the rocker arm 9 is pivoted about the second axis (as indicated by B in fig. 2).

Claims:

1. Tracking system (1) for tracking a mobile robot (2), in particular a mobile construction robot at a construction site, comprising:

- a tacheometer (3) configured to track an optical marker (4); and

- a mobile robot (2), wherein the mobile robot (2) comprises:

- a robot base (5); and

- a multi-axis robot arm (6) arranged on the robot base (5), wherein the robot arm (6) comprises a plurality of links (7) connected by joints (8), wherein one of the links (7) is configured as a rocker arm (9),

- characterized in that

- the optical marker (4) is mounted on the rocker arm (9) of the robot arm (6), wherein the mobile robot (2) is configured to move the rocker arm (9) such that the optical marker (4) is moved to at least a first position, a second position and a third position relative to the robot base (5).

2. Tracking system (1) according to claim 1, characterized in that the multi-axis robot arm (6) comprises at least a first link (21) and a second link (22), wherein the first link (21) is connected to the robot base (5) via a first joint (23), wherein the second link (22) is connected to the first link (21) via a second joint (24), wherein the second link (22) is configured as the rocker arm (9).

3. Tracking system (1) according to claim 2, characterized in that the first joint (23) provides a first degree of freedom of movement, wherein the second joint (24) provides a second degree of freedom of movement, such that the movement of the rocker arm (9) with respect to the robot base (5) has the first degree of freedom and the second degree of freedom.

4. Tracking system (1) according to anyone of the previous claims, characterized in that the rocker arm (9) comprises a distal end (29) and a proximal end (28) relative to the robot base (5), wherein the optical marker (4) is arranged at the distal end (29) of the rocker arm (9).

5. Tracking system according to anyone of the previous claims, characterized in that the optical marker (4) is mounted on the rocker arm (9) via an elongated member (10).

6. Tracking system according to claim 5, characterized in that the elongated member (10) comprises a proximal end (11) and a distal end (12) with respect to the robot base (5), wherein the optical marker (4) is arranged at the distal end (12) of the elongated member (10).

7. Tracking system according to claim 5 or 6, characterized in that the elongated member (10) is arranged essentially parallel to the rocker arm (9).

8. Tracking system according to claim 6 or 7, characterized in that the distal end (12) of the elongated member (10) extends beyond the distal end (29) of the rocker arm (9).

9. Tracking system according to anyone of claims 5 to 8, characterized in that the elongated member (10) comprises a main part (26) and an end part (27), wherein the end part (27) is connected to the main part (26) via an adjustable swivel joint (30), wherein the optical marker (4) is arranged on the end part (27).

10. Method for tracking a mobile robot (2), in particular a mobile construction robot at a construction site, wherein the mobile robot (2) comprises a robot base (5) and a multi-axis robot arm (6) arranged on the robot base (5), wherein the multi-axis robot arm (9) comprises a plurality of links (7) connected by joints (8), wherein one of the links (7) is configured as a rocker arm (9), with the steps:

- providing a tacheometer (3), in particular at the construction site, wherein the tacheometer (3) is configured to track an optical marker (4);

- moving an optical marker (4) mounted on the robot arm (6) of the mobile robot (2) to at least a first position, a second position and a third position relative to the robot base (5) by means of the robot arm (6);

- tracking the optical marker (4) by means of the tacheometer (3) in at least the first position, the second position and the third position relative to the tacheometer (3); and
- determining a position and an orientation of the robot base (5) based on the tracked first position, the tracked second position and the tracked third position of the optical marker (4),
characterized in that
the optical marker (4) is mounted on the rocker arm (9).

11. A mobile robot (2), in particular a mobile construction robot, comprising:

- a robot base (5); and
- a multi-axis robot arm (6) arranged on the robot base (5), wherein the robot arm (6) comprises a plurality of links (7) connected by joints (8), wherein one of the links (7) is configured as a rocker arm (9),
- an optical marker (4) mounted on the robot arm (6), the optical marker (4) being arranged for tracking with a tacheometer (3),
characterized in that
the optical marker (4) is mounted on the rocker arm (9) of the robot arm (6), wherein the mobile robot (2) is configured to move the rocker arm (9) such that the optical marker (4) is moved to at least a first position, a second position and a third position relative to the robot base (5).

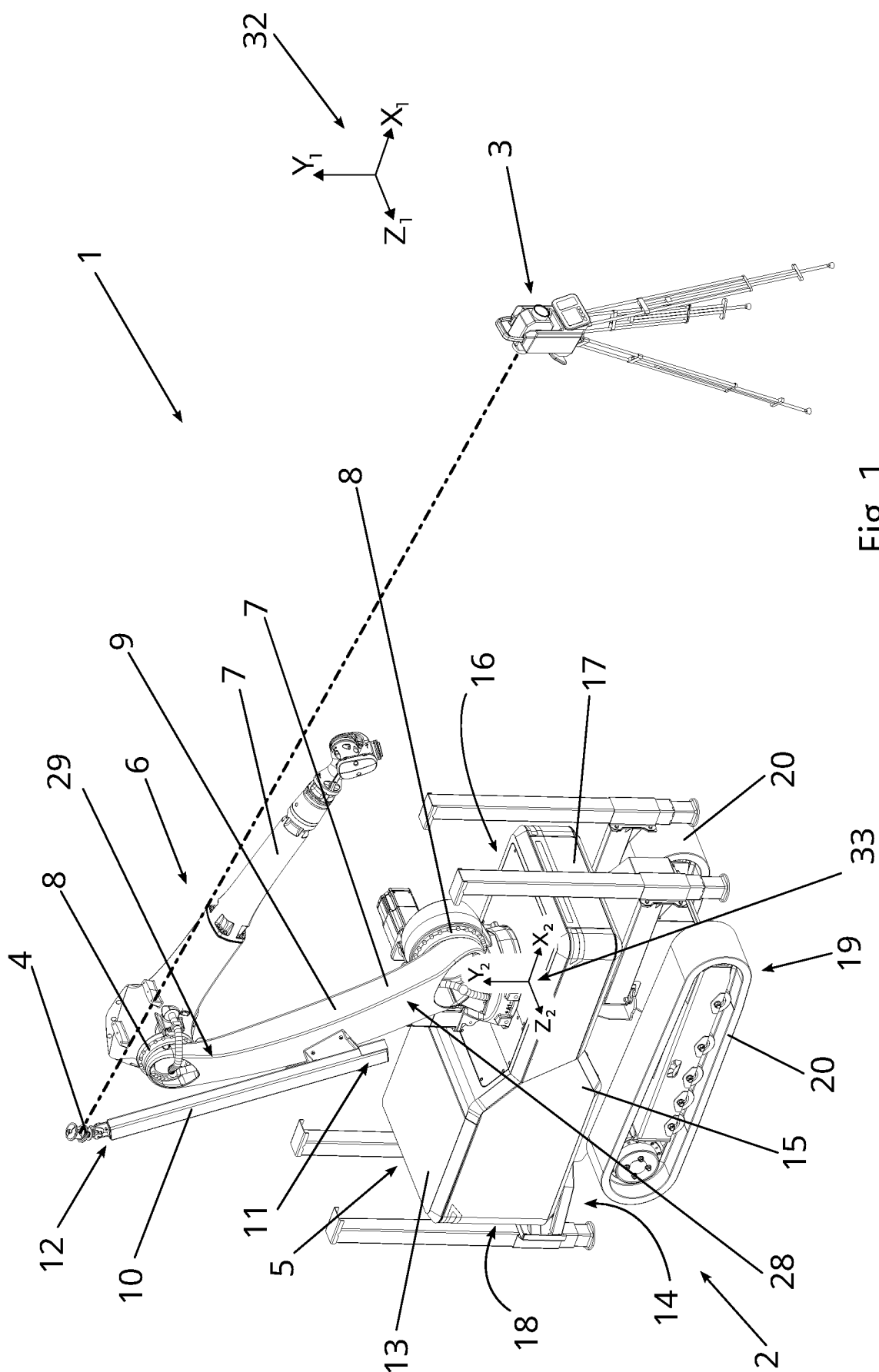


Fig. 1

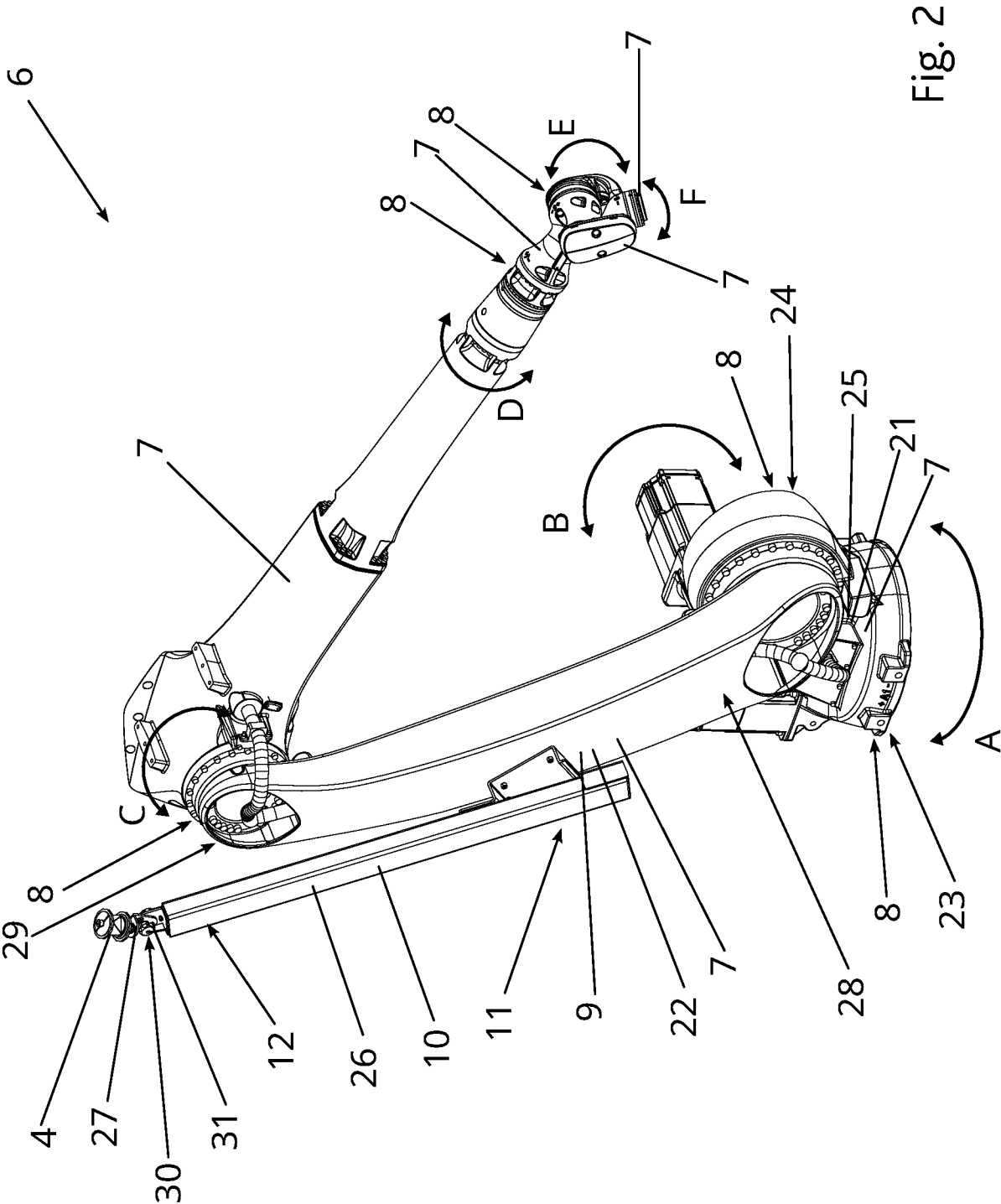


Fig. 2

INTERNATIONAL SEARCH REPORT

International application No
PCT/EP2024/068260

A. CLASSIFICATION OF SUBJECT MATTER

INV. B25J13/08

ADD. B25J9/16

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)

B25J G05B

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

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

EPO-Internal

C. DOCUMENTS CONSIDERED TO BE RELEVANT

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Y	WO 2020/038779 A1 (HILTI AG [LI]) 27 February 2020 (2020-02-27) cited in the application	1-4, 10, 11
A	figure 1 page 1 - page 4 page 6 - page 8 -----	5-9
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Further documents are listed in the continuation of Box C.



See patent family annex.

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"X" document of particular relevance;; the claimed invention cannot be considered novel or cannot be considered to involve an inventive step when the document is taken alone

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"&" document member of the same patent family

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11 July 2024

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INTERNATIONAL SEARCH REPORT

International application No
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C(Continuation). DOCUMENTS CONSIDERED TO BE RELEVANT		
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