

ALLNAMES:(Shenzhen Yuejiang Technology Co., Ltd.)

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Sort: Relevance

Per page: 10

View: All

1 / 51

Machine translation

1. [WO/2020/135608](#) INDUSTRIAL ROBOT DEMONSTRATION TRACK RECURRENCE METHOD AND SYSTEM AND ROBOT WO - 02.07.2020Int.Class [B25J 9/22](#) Appl.No PCT/CN2019/128774 Applicant SHENZHEN YUEJIANG TECHNOLOGY CO., LTD. Inventor LIN, Jionghui

The present application is applicable to the technical field of robots, and provided thereby are an industrial robot demonstration track recurrence method and system and a robot, the method comprising: collecting various joint information of a robot, and acquiring orientation information of a tail end orientation according to the various joint information of the robot; fitting the orientation information, and obtaining a continually recurring track; calculating the operating speed of the recurring track according to the recurring track; planning the speed of the recurring track according to the motion speed of the recurring track; and obtaining position information of the recurring track in each interpolation period according to a speed planning result, and controlling the robot to move according to the position information. Thus, the joint information of the robot is collected, fitting is carried out according to wave-filtered orientation information, and a continually recurring track is thus obtained, which reduces errors in the tail end orientation and simultaneously guarantees that the curvature of the recurring track is continuous. The speed of the generated recurring track is planned, so as to guarantee that the speed in the track recurring process is controllable.

2. [205644180](#) SOFT POWER -OFF CONTROL CIRCUIT AND ARM DEVICE CN - 12.10.2016Int.Class [G05B 19/042](#) Appl.No 201620465467.8 Applicant SHENZHEN YUEJIANG TECHNOLOGY CO., LTD. Inventor LIU PEICHAO

The utility model provides a driver is connected, including connect the power port with of soft power -off control circuit and arm device, circuit and robotic arm switch module between the driver, with power button and control that the power port is connected robotic arm motion and the controller that resets, the detection port of controller connects the power button, the output port of controller connects the switch module, wherein, the controller detects during the power button disconnection, control after robotic arm resets, control again the switch module turn -offs. Detect switch's state through the controller, when judging that it be off -state, deenergization again after can the control machinery arm reseing avoids the arm to receive effect of gravity, and joint department moment is great, and the arm can free falling, may cause arm or external equipment to damage, and this scheme simply reliably, and is with low costs.

3. [205521457](#) SNATCH MECHANISM AND ROBOT CN - 31.08.2016Int.Class [B25J 15/02](#) Appl.No 201620105900.7 Applicant Shenzhen Yuejiang Technology Co., Ltd. Inventor Liu Peichao

The utility model provides a snatch mechanism and robot, wherein, snatch the mechanism including snatching the mounting bracket, snatch the driver, swinging boom and a pair of arm lock subassembly, it is fixed in and snatches the mounting bracket to snatch the driver, the swinging boom rotates along with the pivot with the pivot fixed connection who snatches the driver, the swinging boom includes the intermediate junction portion with pivot fixed connection, each arm lock subassembly includes clamping jaw and connecting rod, the one end of connecting rod articulates in the clamping jaw, the other end articulates in the swinging boom, and two connecting rods articulate the both sides of intermediate junction portion on the swinging boom respectively, the clamping jaw is including the clamping part that is used for the centre gripping article, and with snatch the mounting bracket and articulated and articulate the portion around its pivoted fixed point down in the drive of connecting rod, wherein, the clamping -force's of production direction sets up in opposite directions during two clamping part centre gripping articles. Wherein, articulated connection structure is adopted in the connection of snatching between mounting bracket, clamping jaw, connecting rod and the swinging boom, makes the junction need not to reserve the free gap to avoid the clamping jaw to rock.

4. [WO/2021/258355](#) ENDOSCOPE SUPPORTING ARM, ENDOSCOPE SUPPORTING DEVICE AND OPERATING TABLE WO - 30.12.2021Int.Class [A61B 34/30](#) Appl.No PCT/CN2020/098202 Applicant SHENZHEN YUEJIANG TECHNOLOGY CO., LTD. Inventor LIU, Peichao

An endoscope supporting arm [100], an endoscope supporting device and an operating table. The endoscope supporting arm [100] comprises a tail end, and the endoscope supporting arm [100] comprises a plurality of joints [10] and a plurality of rigid arm bodies [20], wherein two adjacent rigid arm bodies [20] are connected by means of one joint [10], each joint [10] comprises a rotating shaft [11] and an electric control locking apparatus [12], a first end of the rotating shaft [11] is rotatably connected to one rigid arm body [20] at the joint [10], a second end of the rotating shaft [11] and the other rigid arm body [20] at the joint [10] also rotate, the rigid arm body [20] rotates around the central axis of the rotating shaft [11] relative to the previous rigid arm body [20], and the electric control locking apparatus [12] is configured to lock or release the rotating shaft [11]. The problem of the rigidity of the endoscope supporting arm [100] of an existing endoscope supporting device being insufficient, such that a stable pose of an endoscope cannot be kept, is solved.

5. [107081758](#) MOTION CONTROL METHOD OF MECHANICAL ARM, MICROCONTROLLER AND STORAGE MEDIUM CN - 22.08.2017Int.Class [B25J 9/16](#) Appl.No 102017000379873 Applicant SHENZHEN YUEJIANG TECHNOLOGY CO., LTD. Inventor LIU PEICHAO

The embodiment of the invention discloses a motion control method of a mechanical arm. The problem that in the application interface, interface buttons cannot be in intuitive corresponding to the rotating direction of a mechanical arm rotating shaft is solved. The method in the embodiment comprises the steps that a microcontroller on the mechanical arm obtains the first rotating direction, from a control device, of a rotary knob on the control device and the first angle increment in the first rotating direction; the first rotating direction of the rotary knob is converted into the second rotating direction of a target rotating shaft of the mechanical arm; the first angle increment of the rotary knob is converted into the rotating angle of the target rotating shaft in the second rotating direction; rotating motion data are generated; the rotating motion data are sent to a drive expansion board of the mechanical arm. The invention further provides a microcontroller on the mechanical arm and a storage medium.



6. [206690074](#) ELIMINATE ROTATING BASE OF ROBOT OF RETURN STROKE DEVIATION

CN - 01.12.2017

Int.Class [B25J 9/00](#) Appl.No 201621096886.5 Applicant SHENZHEN YUEJIANG TECHNOLOGY CO. LTD. Inventor LIU PEICHAO

The utility model relates to a robot technology field especially relates to eliminate rotating base of robot of return stroke deviation for the installation has the motor and the output of main shaft the power of motor, its characterized in that: including the shell, fixed mounting that are equipped with the installation cavity in the internal fixed plate of installation cavity and locating the installation cavity internal and with motor fixed connection is in order to follow output power's rotor plate is selected to the motor, the fixed plate is equipped with first via hole, the rotor plate be equipped with with the corresponding second via hole of first via hole, the main shaft passes in proper order the second via hole with first via hole and with fixed plate fixed connection, be fixed with tension device between rotor plate and the fixed plate, tension device overlaps on the main shaft.

7. [205630680](#) ARM AND ROBOT

CN - 12.10.2016

Int.Class [B25J 18/00](#) Appl.No 201620465910.1 Applicant SHENZHEN YUEJIANG TECHNOLOGY CO., LTD. Inventor LIU PEICHAO

The utility model relates to a robot technology field especially relates to arm and robot, and the arm is including relative first curb plate and the second curb plate that sets up, the arm still includes the top mounting panel, the both sides of top mounting panel respectively with the upper end of first curb plate with the upper end of second curb plate is connected, just the top mounting panel with first curb plate with second curb plate integrated into one piece. The utility model discloses a first curb plate and second curb plate are connected through setting up the top mounting panel to the arm, and top mounting panel, first curb plate and second curb plate three integrated into one piece and make to can strengthen the structural strength of whole arm, during the use, the top mounting panel of arm, first curb plate and second curb plate all difficult the production deform, and the top mounting panel can also regard as other electronic component's mounting substrate to use for the application of arm is more nimble, and application scope is wider, and adaptability is better.

8. [W0/2020/135607](#) SPATIAL PATH TRANSITIONING METHOD FOR INDUSTRIAL ROBOT, SYSTEM, AND ROBOT

W0 - 02.07.2020

Int.Class [B25J 9/16](#) Appl.No PCT/CN2019/128773 Applicant SHENZHEN YUEJIANG TECHNOLOGY CO., LTD. Inventor LIN, Jionghui

Provided are a spatial path transitioning method for an industrial robot, a system, and a robot. The method comprises: constructing a transition region curve according to a linear motion path, an arc curve motion path, and a transition normalization parameter; calculating a boundary speed of the transition region curve according to a sagitta error and a maximum acceleration; and performing optimization on the transition region curve according to the boundary speed, acquiring, on the basis of the transition region curve, position information of each interpolation period in a transition region, and controlling a robot to move according to the position information. The invention constructs the transition region curve and imposes a constraint on the boundary speed, so as to achieve consistency of a transition path at both a low speed and a high speed. A traveling speed on a path in the transition region is determined according to the sagitta error and the maximum acceleration, such that a transition speed is guaranteed to be within an allowable range, and a continuous curvature change is achieved where the transition path and an original path are joined, thereby achieving a smooth transition.

9. [206925865](#) PLANE JOINT ROBOT

CN - 26.01.2018

Int.Class [B25J 11/00](#) Appl.No 201720599155.0 Applicant SHENZHEN YUEJIANG TECHNOLOGY CO., LTD. Inventor LIU PEICHAO

The utility model provides a plane joint robot and plane joint robot, wherein, plane joint robot includes electric control assembly and automatically controlled arrangement structure, the holding chamber that is used for depositing electric control assembly is offered to the automatically controlled arrangement structure of, and the spliced eye in intercommunication outside and holding chamber is offered to automatically controlled arrangement structure in its lateral wall, plane joint robot includes the plug assemblies who pegs graft the cooperation and be connected with the spliced eye with the dismantlement of automatically controlled arrangement structure shell, and electric control assembly connects in plug assemblies. Plane joint robot passes through spliced eye and plug assemblies's setting, dismantling the in-process, need not to open automatically controlled arrangement structure, has reduced the step of opening automatically controlled arrangement structure, has improved plane joint robot's dismantlement efficiency. Based on the utility model discloses the structure reduces the whole volume of plane joint robot, is favorable to plane joint robot miniaturized, and has improved electric control assembly's dismantlement and assembly efficiency.

10. [206925888](#) JOINT CONNECTION STRUCTURE AND PLANE JOINT ROBOT

CN - 26.01.2018

Int.Class [B25J 17/02](#) Appl.No 201720598072.X Applicant SHENZHEN YUEJIANG TECHNOLOGY CO., LTD. Inventor LIU PEICHAO

The utility model provides a joint connection structure and plane joint robot, wherein, joint connection structure includes first articulated arm, the second joint arm, drive unit and switching subassembly, first articulated arm includes first connecting portion, first connecting portion include position relation set up from top to bottom and the interval sets up first connection support arm and second connection support arm, the second joint arm is including locating the second connecting portion between first connection support arm and the second connection support arm, the switching subassembly including be fixed in the second connect the setting element of support arm and cup joint in the setting element and with the bearing of the coaxial setting of drive output shaft, the spacing hole with bearing fit is seted up to the second connecting portion, the inner circle of bearing cup joints in the setting element with fastening, cup joint in spacing hole the outer lane of bearing. Canbear the within range at drive output shaft moment of torsion, the shake can be avoided effectively in the moment of torsion increase, and beyond the drive output shaft moment of torsion scope of bearing, increases the scope at the moment of torsion and within the scope that the bearing bore, still can not cause the damage to drive unit.

