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Attorneys for Plaintiffs
 Subo Automation Inc. and
 Milos Misha Subotincic

UNITED STATES DISTRICT COURT
CENTRAL DISTRICT OF CALIFORNIA
EASTERN DIVISION

MILOS MISHA SUBOTINCIC, an
 individual, and
 SUBO AUTOMATION INC., an
 Ontario (Canada) corporation,

 Plaintiffs,

CASE NO. EDCV 13-01459 MMM
 (SPx)

**FIRST AMENDED COMPLAINT
 FOR PATENT INFRINGEMENT**

vs.

MCKEE FOODS CORPORATION,
 a Tennessee corporation; and DOES
 1 THROUGH 10, inclusive,

 Defendants.

DEMAND FOR JURY TRIAL

BY FAX

FIRST AMENDED COMPLAINT AND JURY TRIAL DEMAND

LEECH TISHMAN FUSCALDO & LAMPL, LLP
 626.817.7500

COMPLAINT

Plaintiffs Milos Misha Subotincic, and Subo Automation Inc., bring this action against McKee Foods Corporation, and for their causes of action, allege as follows:

THE PARTIES

1. Plaintiff Milos Misha Subotincic (“Subotincic”) is a Canadian citizen having an address at 83 Riverwood Parkway, Toronto, Ontario, Canada M8Y4E4.

2. Plaintiff Subo Automation Inc. (“Subo”) is a corporation established and existing under the laws of the province of Ontario, Canada, with a principal place of business at 83 Riverwood Parkway, Toronto, Ontario, Canada M8Y4E4. Depending on the context in which it is used herein, the term “Plaintiffs” is intended to include both Plaintiffs Subotincic and Subo.

3. Defendant McKee Foods Corporation (“McKee”) is a corporation established and existing under the laws of Tennessee, with a principal place of business at 10260 McKee Road, Collegedale, Tennessee 37315.

4. At this time, the true names and capacities of Doe Defendants 1-10 are not known to Plaintiffs, and Plaintiffs therefore sue them under fictitious names. When the actual identities of Does 1 through 10 are determined, Plaintiffs intend to seek leave of Court to amend this Complaint to name such persons as Doe Defendants. Plaintiffs are informed and believe, and thereon allege, that Does 1 through 10 participated in one or more of the wrongful acts described herein, and/or are responsible in some way for one or more of the wrongful acts and resulting damages alleged herein. Accordingly, depending on the context in which it is used herein, the term “Defendants” is intended to include not only Defendant McKee, but also any other Defendants or any individuals or other entities acting on behalf of or in coordination with the named Defendant regarding the matters discussed herein.

JURISDICTION AND VENUE

5. This action arises under the patent laws of the United States, Title 35 United States Code, particularly §§ 271 and 281. This Court has jurisdiction over the claim for patent infringement under 28 U.S.C. §§ 1331 and 1338(a).

6. Venue is proper in this judicial District under 28 U.S.C. § 1391 and/or 1400(b) as this action relates to patents, and Defendants, on information and belief, have committed acts of infringement here.

7. Personal jurisdiction exists generally over the Defendants because they have sufficient minimum contacts with the forum as a result of business conducted within the State of California and within the Central District of California. Personal jurisdiction also exists specifically over each of the Defendants because each, directly or through subsidiaries or intermediaries, makes, uses, sells, and offers for sale, products or services within the State of California and within the Central District of California, that infringe U.S. Patent No. 8,240,726.

THE PATENT

8. On August 14, 2012, United States Patent No. 8,240,726, entitled “End Effector With Multiple Pick-Up Members” (“the ‘726 patent”) was duly and legally issued by the United States Patent and Trademark Office. A true and correct copy of the ‘726 patent is attached as Exhibit A.

9. Pursuant to 35 U.S.C. § 282, the ‘726 patent is presumed valid.

10. Subotincic is the inventor and owner of the entire right, title, and interest in the ‘726 patent, including the right to recover damages for past, present and future infringement.

11. Plaintiff Subo Automation, Inc. is, and remained at all relevant times, the exclusive licensee of the ‘726 Patent.

FIRST CAUSE OF ACTION

(patent infringement)

1 12. Defendants have been and are now making, using, selling, offering
2 for sale within the United States, or importing into the United States, end effector
3 tools that infringe one or more claims of the '726 patent.

4 13. By so making, using, selling, offering to sell within the United
5 States, or importing into the United States the aforementioned products,
6 Defendants have infringed and continue to infringe the '726 patent, either literally
7 or by equivalents, and either directly or indirectly by inducing infringement or
8 contributing to the infringement of the '726 patent.

9 14. With respect to certain claims of the '726 patent, on information and
10 belief, to the extent that Defendants are guilty of contributing to the infringement
11 of those claims of the '726 patent, Defendants have been and are now making,
12 using, selling, offering for sale within the United States, or importing into the
13 United States, end effector tools, or portions thereof, that are especially made or
14 especially adapted for use in an infringement of such certain claims, and are not
15 staple articles or commodities of commerce suitable for substantial noninfringing
16 use under 35 U.S.C. § 271(c). By way of example, and not by way of limitation,
17 on information and belief, Defendants buy end effector tools from their suppliers,
18 which are then installed on robots of Defendants, the combination of which
19 infringes claims of the '726 patent that require the combination of a robot and an
20 end effector.

21 15. On information and belief, Defendants knew of the '726 patent, and
22 knew the combination of the end effector and robot infringes those claims of the
23 '726 patent.

24 16. Plaintiffs allege that the end effector tool used by Defendants is a
25 material part of the invention, and, on information and belief, Defendants knew
26 the tools were specifically made or adapted for an infringing use. On information
27 and belief, Defendants intended to infringe the patent and knew that their acts
28 constituted infringement.

1 17. With respect to certain claims of the ‘726 patent, on information and
2 belief, to the extent that Defendants are guilty of inducing infringement of those
3 claims of the ‘726 patent, Defendants have been and are now making, using,
4 selling, offering for sale within the United States, or importing into the United
5 States, end effector tools, or portions thereof, that are especially made or
6 especially adapted for use in an infringement of such certain claims by
7 Defendants’ customers who infringe those claims, and not staple articles or
8 commodities of commerce suitable for substantial noninfringing use under 35
9 U.S.C. § 271(b). By way of example, and not by way of limitation, on
10 information and belief, Defendants induced their supplier to sell them end
11 effector tools, which are then installed on Defendants’ robots, the combination of
12 which infringes claims of the ‘726 patent that require the combination of a robot
13 and an end effector. On information and belief, Defendants knew of the ‘726
14 patent, and knowingly induced their supplier to infringe those claims of the ‘726
15 patent.

16 18. Defendants’ acts of infringement, inducement of infringement, and
17 contributory infringement, of the ‘726 patent as alleged above have injured
18 Plaintiffs and Plaintiffs are entitled to recover damages adequate to compensate
19 them for that infringement, which in no event can be less than a reasonable
20 royalty.

21 19. On information and belief, Defendants have been aware of the ‘726
22 Patent and their infringement thereof since issuance of the ‘726 Patent. Despite
23 knowledge of their infringement of the ‘726 Patent, Defendants continued to
24 infringe that patent. Defendants acted despite an objectively high likelihood that
25 its actions constituted infringement of the ‘726 Patent. Defendants therefore
26 willfully infringed the ‘726 patent.

27 **PRAYER FOR RELIEF**

28 WHEREFORE, Plaintiffs pray for entry of judgment:

1 A. Declaring that the Defendants have infringed one or more claims of
2 the '726 patent.

3 B. That the Defendants account for and pay to Plaintiffs all damages
4 caused by the infringement of the '726 patent, which by statute can be no less
5 than a reasonable royalty;

6 C. That the Defendants have willfully infringed the '726 patent, and
7 that an award of damages in the highest amount allowed by law be assessed
8 against Defendants for the willful infringement.

9 D. That Plaintiffs be granted their costs, pre-judgment and post-
10 judgment interest on the damages caused to them by reason of the Defendants'
11 infringement of the '726 patent;

12 E. That each of the Defendants, and all those in active participation or
13 concert with them, be preliminarily and permanently enjoined from further acts of
14 infringement, inducing infringement and/or contributory infringement of
15 Plaintiff's '726 patent;

16 F. That Plaintiffs be granted his attorneys' fees in this action;

17 G. That costs be awarded to Plaintiffs;

18 H. That Plaintiffs be granted such other and further relief that is just and
19 proper under the circumstances.

20 Dated: August 19, 2013

21 

22 _____
23 Alan M. Kindred
24 Ivan Posey
25 LEECH TISHMAN FUSCALDO &
26 LAMPL, LLP
27 Attorneys for Plaintiffs Milos Misha
28 Subotincic and Subo Automation Inc.

DEMAND FOR JURY TRIAL

Pursuant to Rule 38(b), F. R. Civ. P., plaintiff hereby demands trial by jury on all issues so triable.

August 19, 2013



Alan M. Kindred
Ivan Posey
LEECH TISHMAN FUSCALDO &
LAMPL, LLP

Attorneys for Plaintiffs Milos Misha
Subotincic and Subo Automation Inc.

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EXHIBIT A



US008240726B2

(12) **United States Patent**
Subotincic

(10) **Patent No.:** **US 8,240,726 B2**

(45) **Date of Patent:** ***Aug. 14, 2012**

(54) **END EFFECTOR WITH MULTIPLE PICK-UP MEMBERS**

(76) Inventor: **Milos Misha Subotincic**, Etobicoke
(CA)

(*) Notice: Subject to any disclaimer, the term of this patent is extended or adjusted under 35 U.S.C. 154(b) by 0 days.

This patent is subject to a terminal disclaimer.

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(21) Appl. No.: **12/214,828**

(22) Filed: **Jun. 23, 2008**

(65) **Prior Publication Data**

US 2009/0066098 A1 Mar. 12, 2009

Related U.S. Application Data

(63) Continuation of application No. 10/420,075, filed on Apr. 22, 2003, now Pat. No. 7,390,040.

(60) Provisional application No. 60/374,408, filed on Apr. 22, 2002.

(51) **Int. Cl.**
A47B 97/00 (2006.01)

(52) **U.S. Cl.** **294/65**; 294/87.1; 198/468.3; 414/627;
414/737

(58) **Field of Classification Search** 414/416.02,
414/749.5, 783, 752.1, 737, 668, 667, 666,
414/658, 627, 226.01, 225.01, 900; 294/87.12,
294/87.1, 65; 198/468.3; 901/40

See application file for complete search history.

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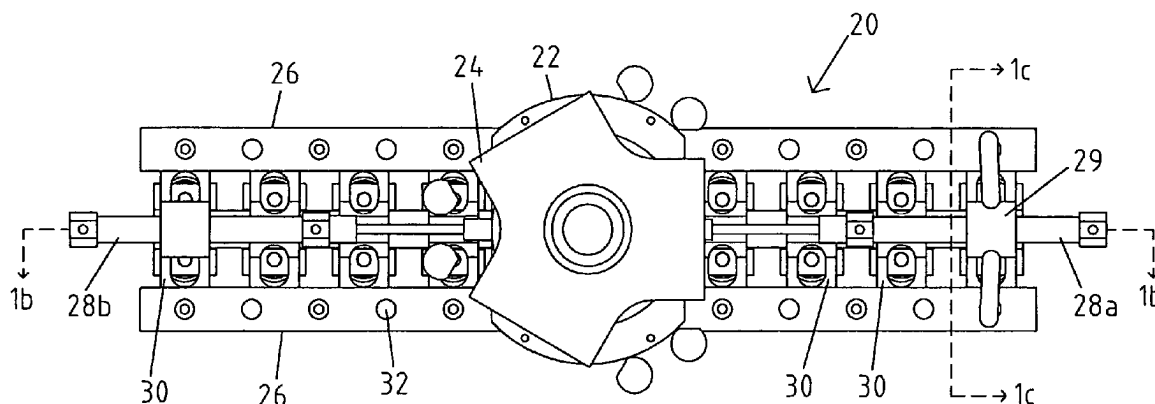
Primary Examiner — Scott Lowe

(74) *Attorney, Agent, or Firm* — Smart & Biggar

(57) **ABSTRACT**

An end effector for use with a moving device has a frame and a plurality of operational members mounted for movement on the frame. The effector also has an actuation mechanism directly connected to a first operational member and is operable to move the first operational member from a first position to a second position, and from the second position to the first position. A linking apparatus is provided for linking the first operational member to a second operational member. The actuation mechanism moves the first operational member from the first position to the second position, and results in the second operational member being moved by the linking apparatus from a third position to a fourth position. The operational members can be pick up members for picking up items at one pitch and releasing them at a second pitch.

45 Claims, 19 Drawing Sheets



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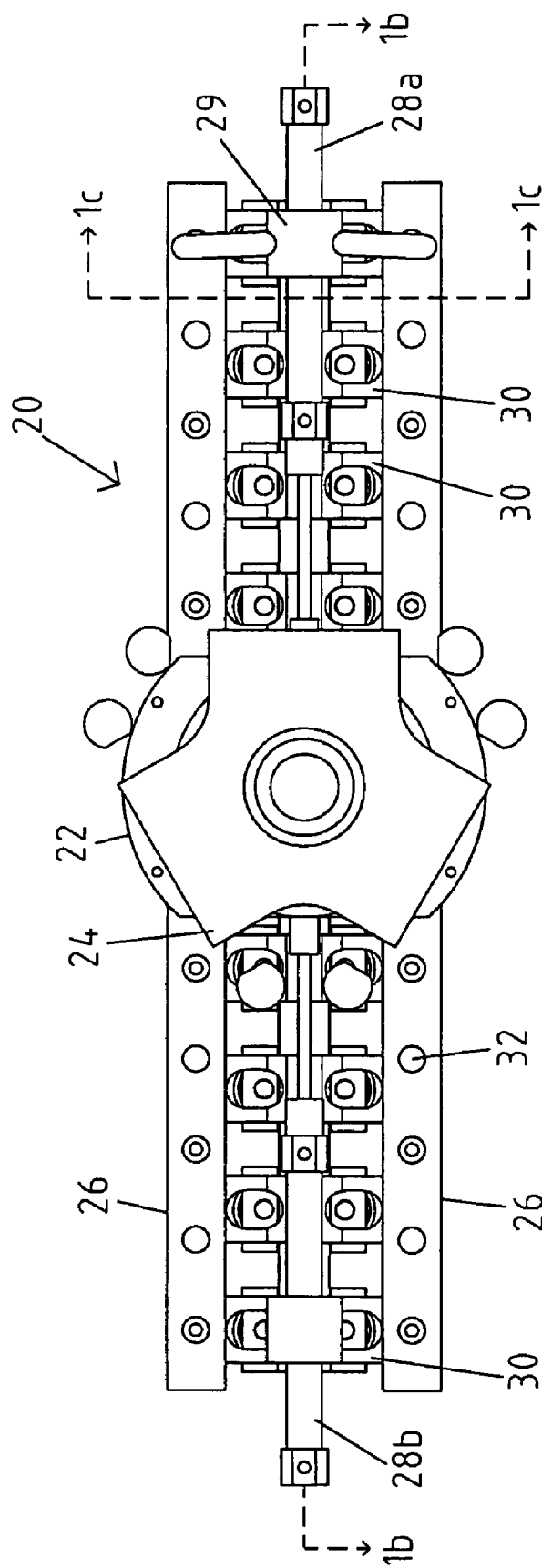


FIG. 1a

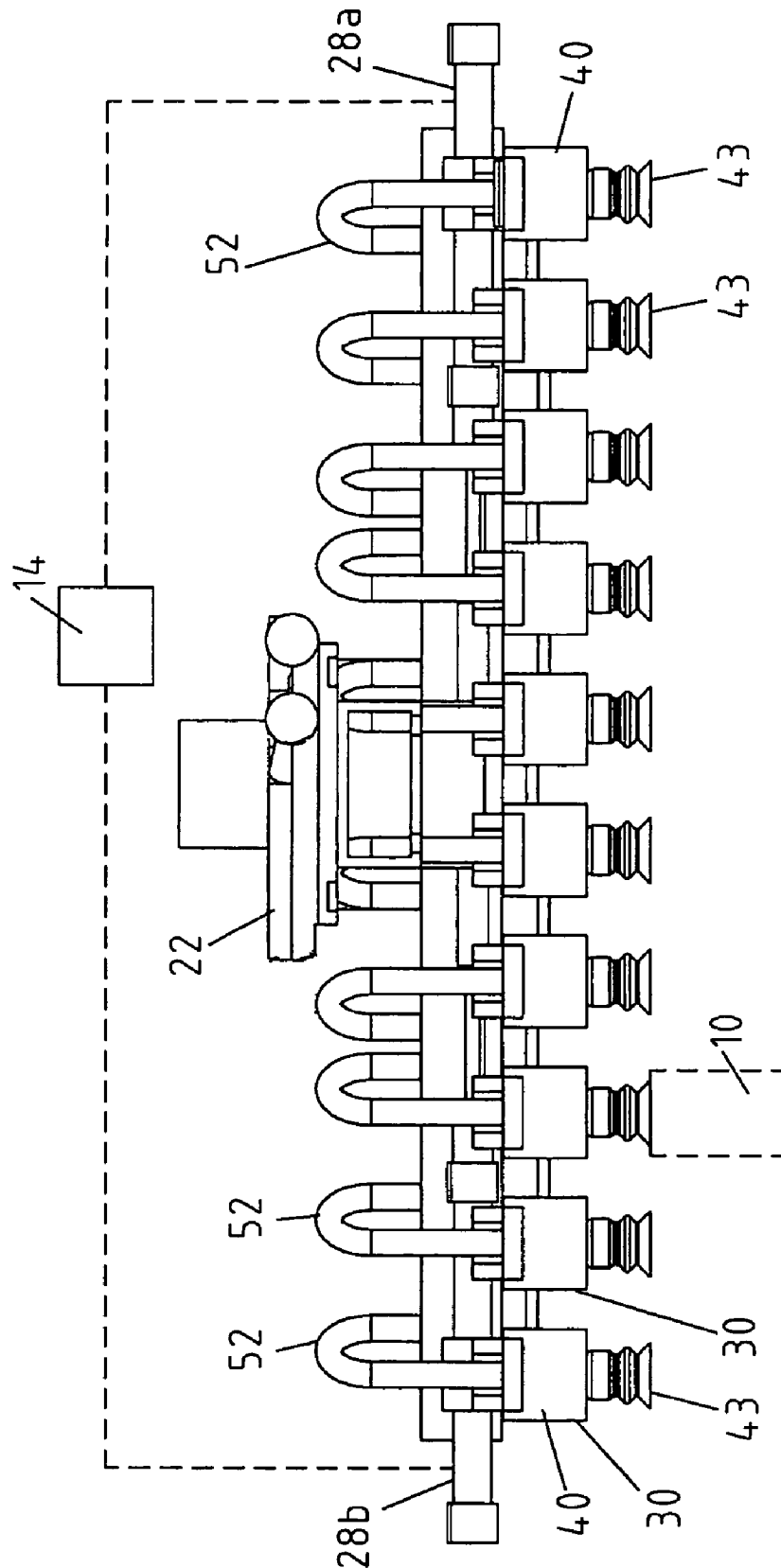


FIG. 1b

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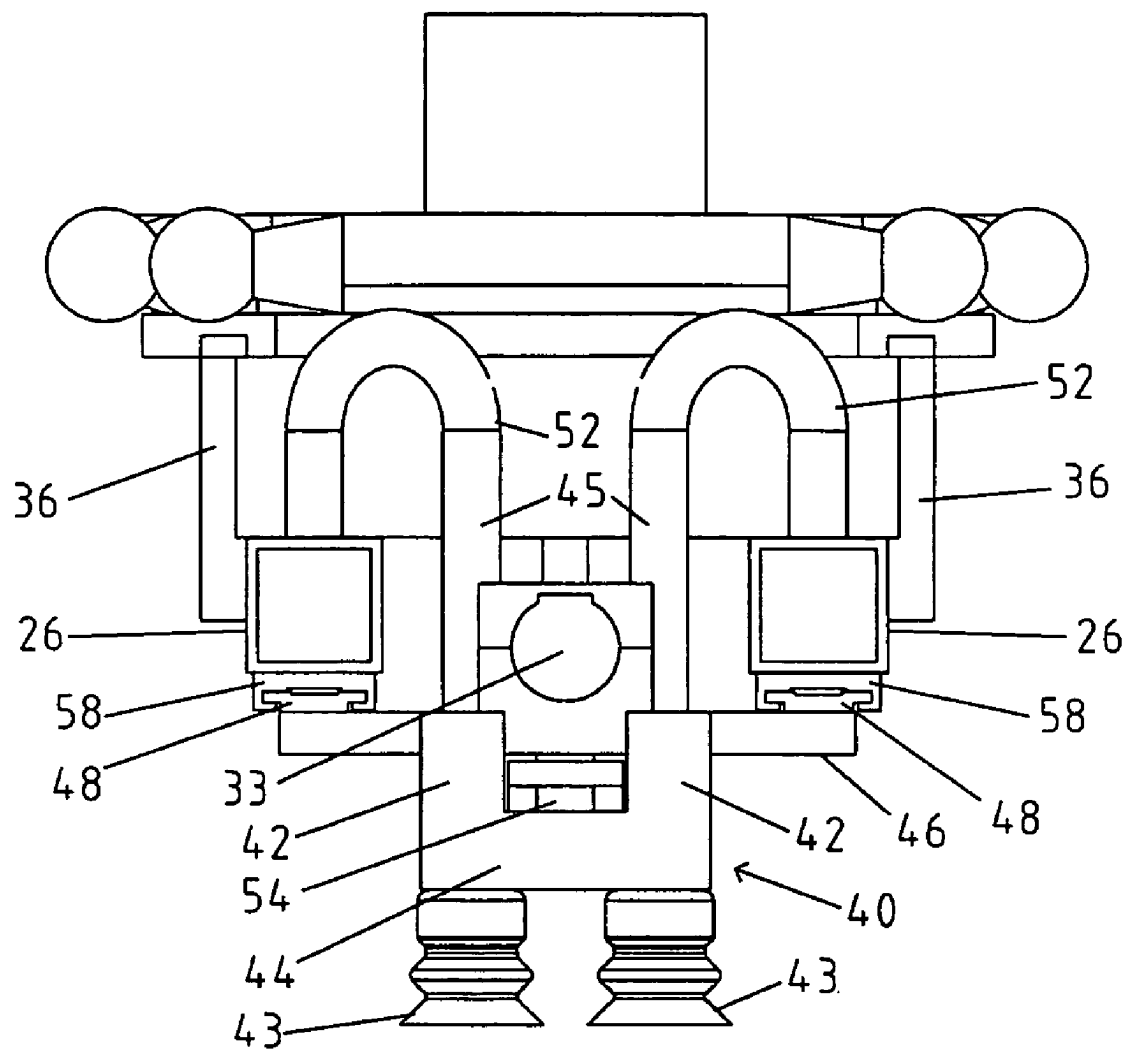


FIG. 1c

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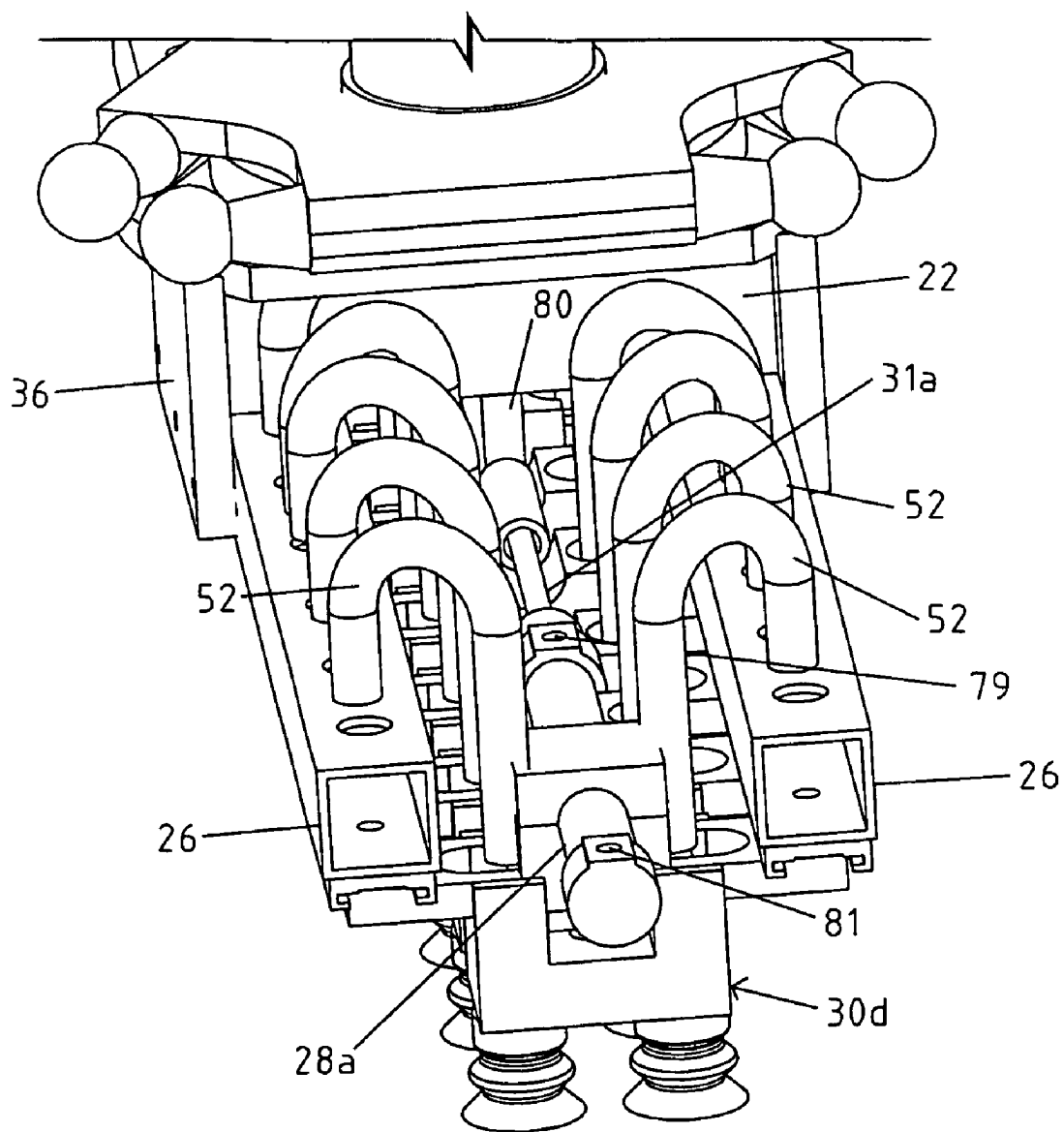
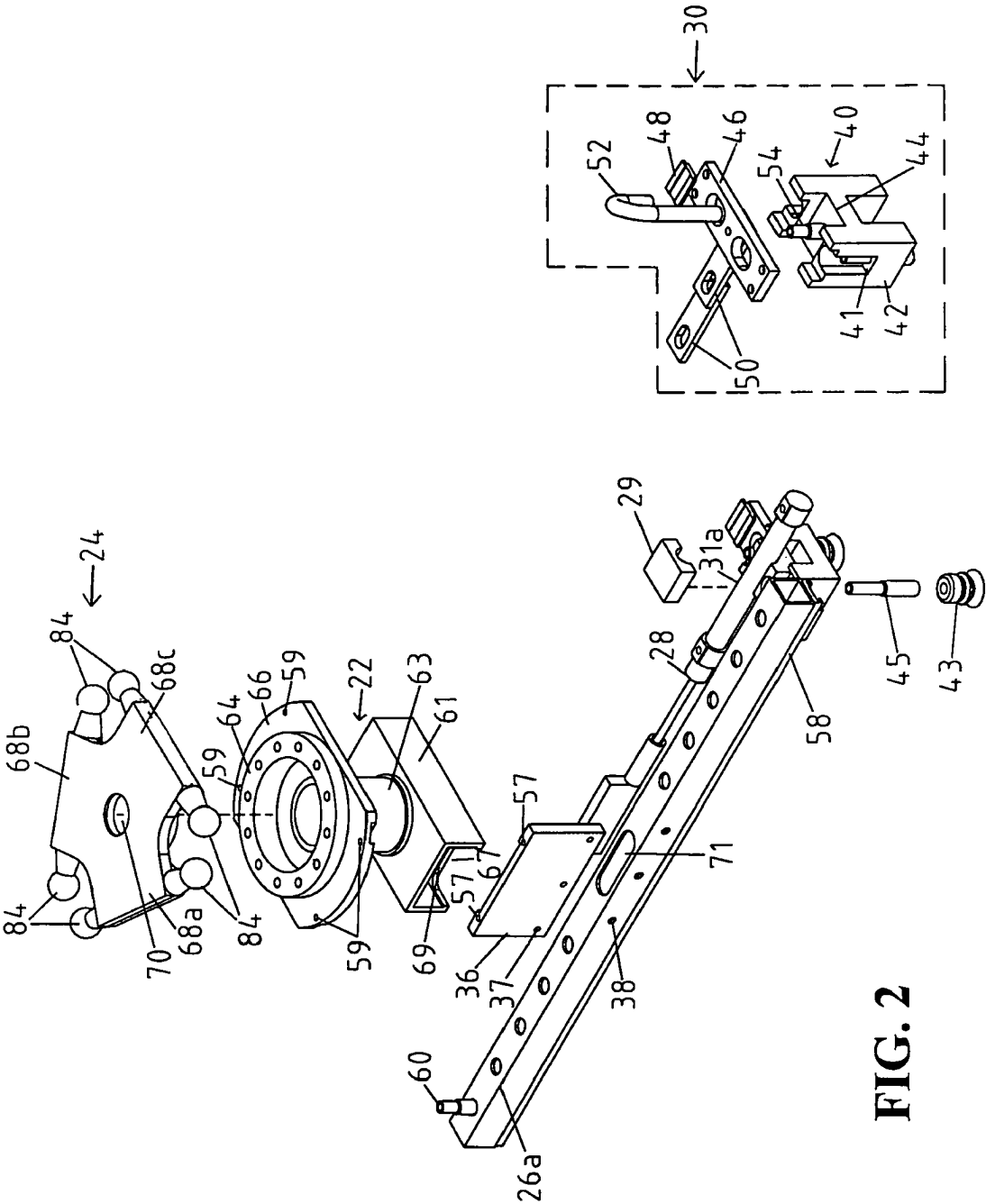


FIG. 1d



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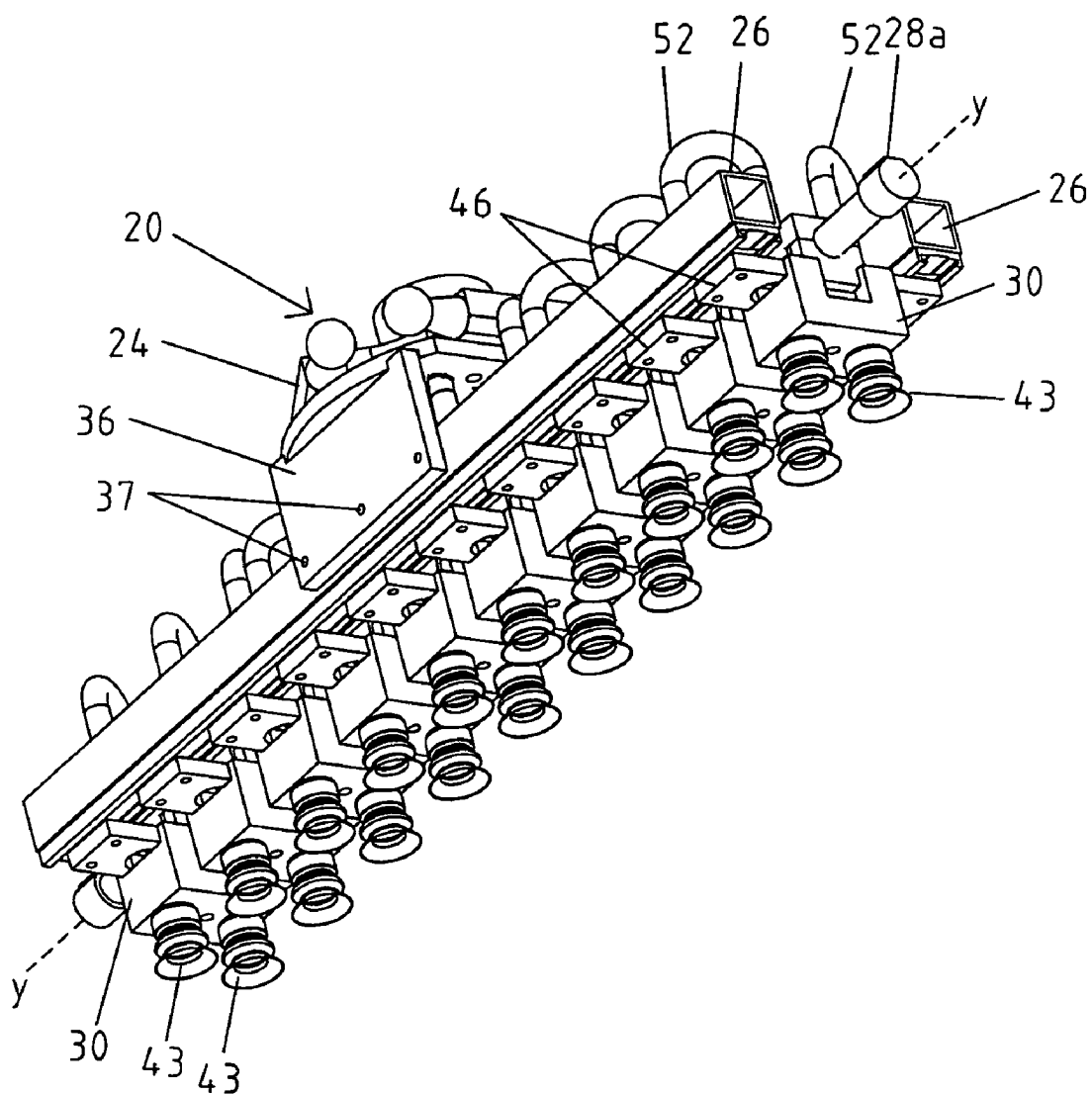


FIG. 3a

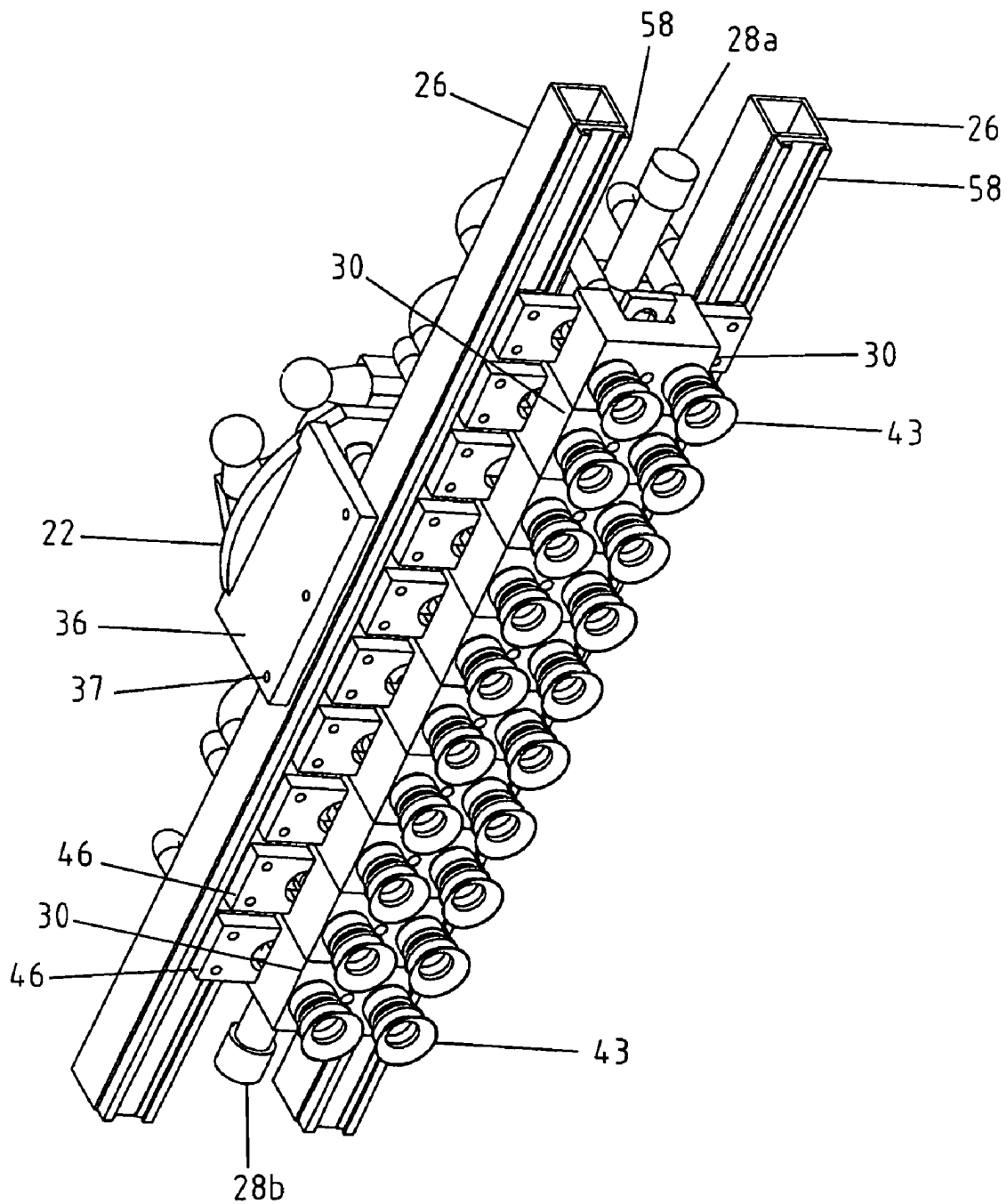


FIG. 3b

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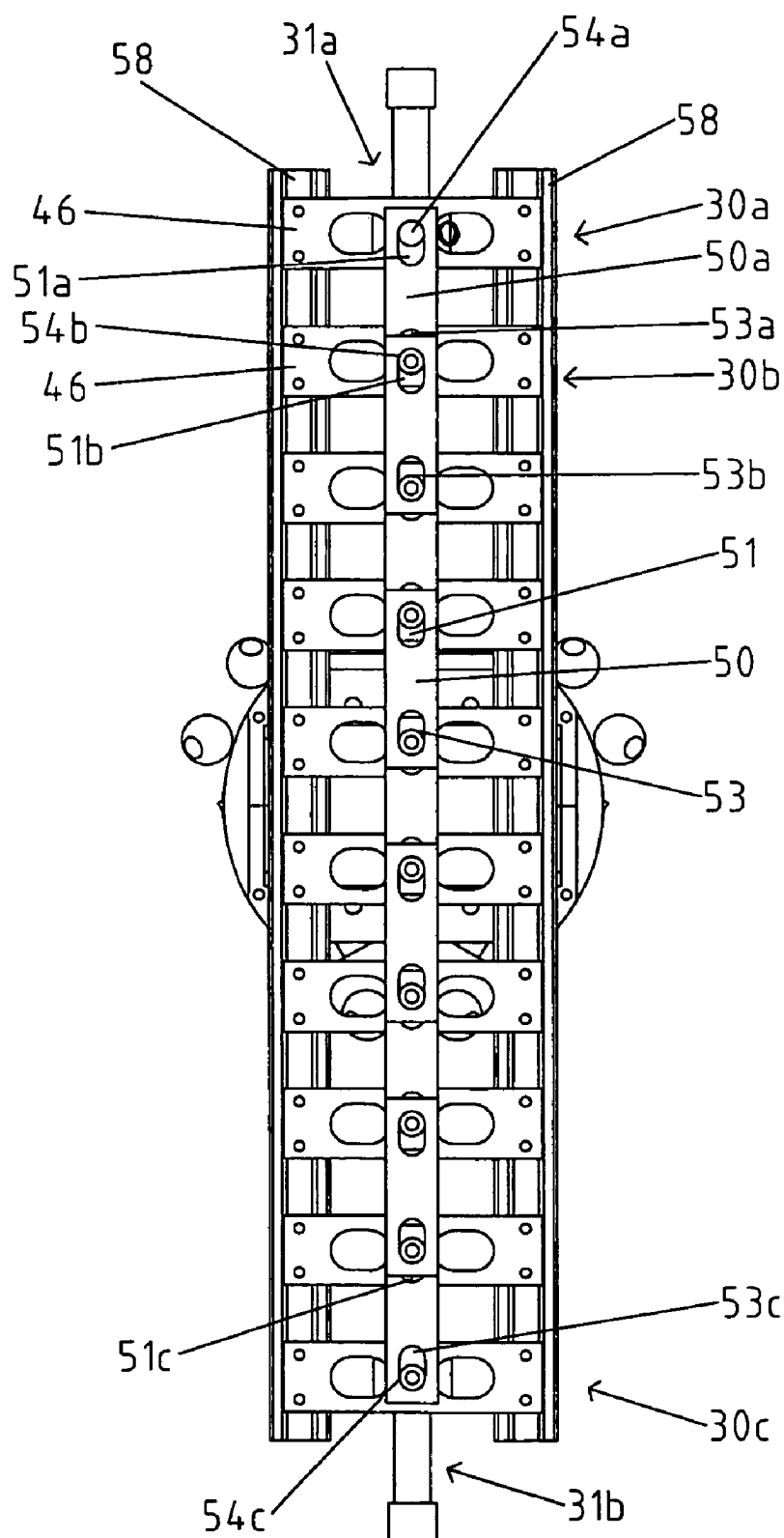
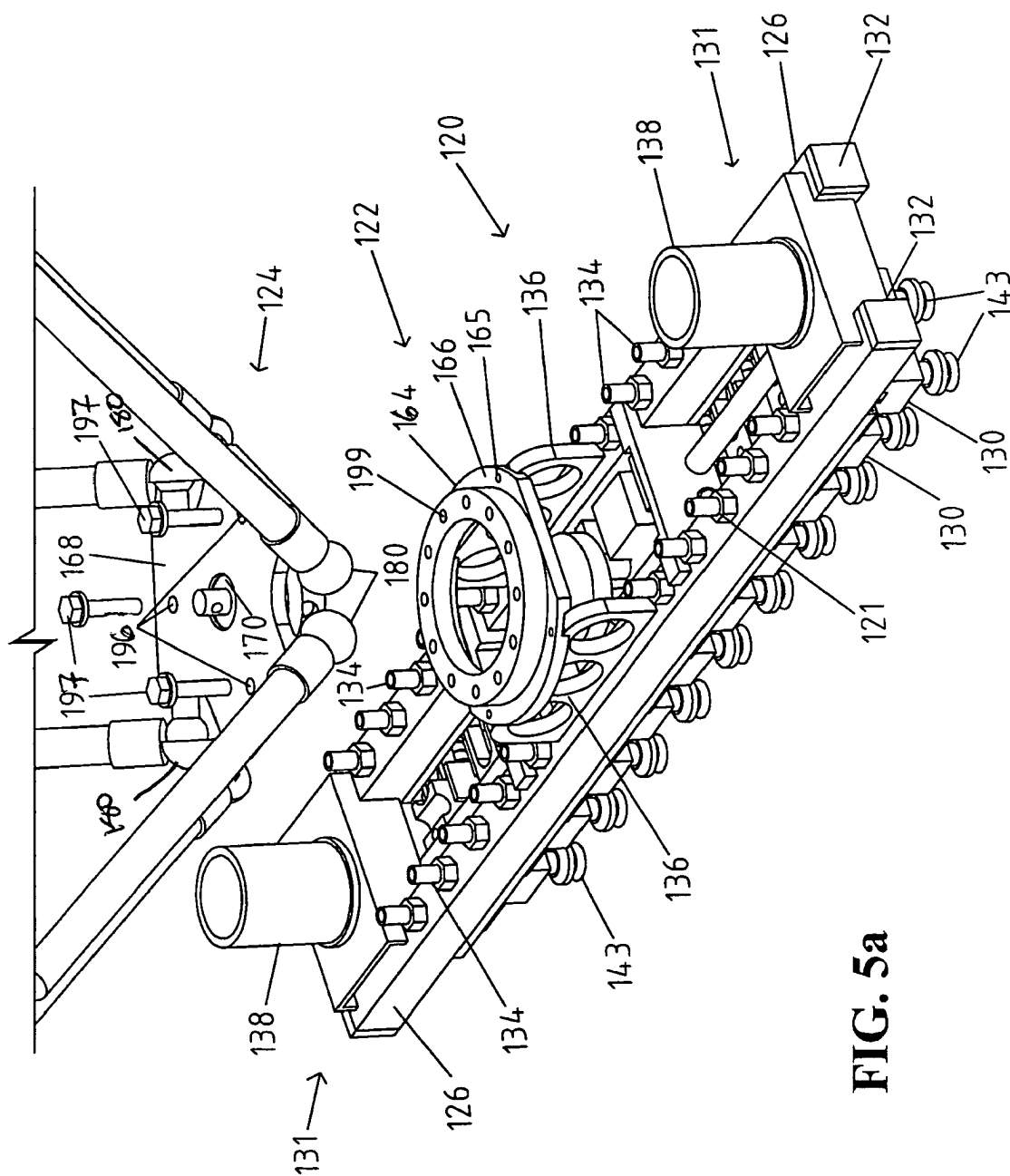


FIG. 4



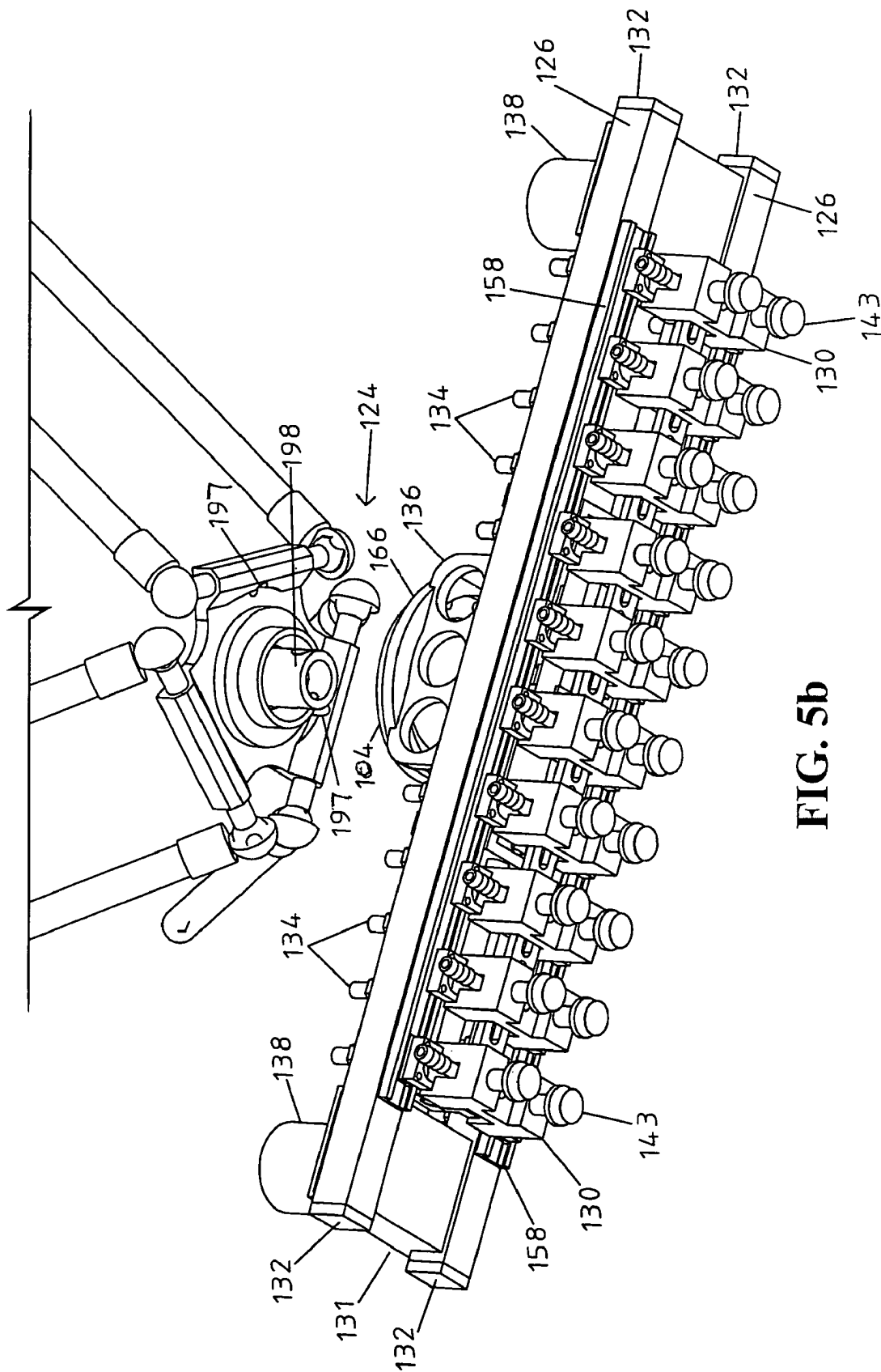


FIG. 5b

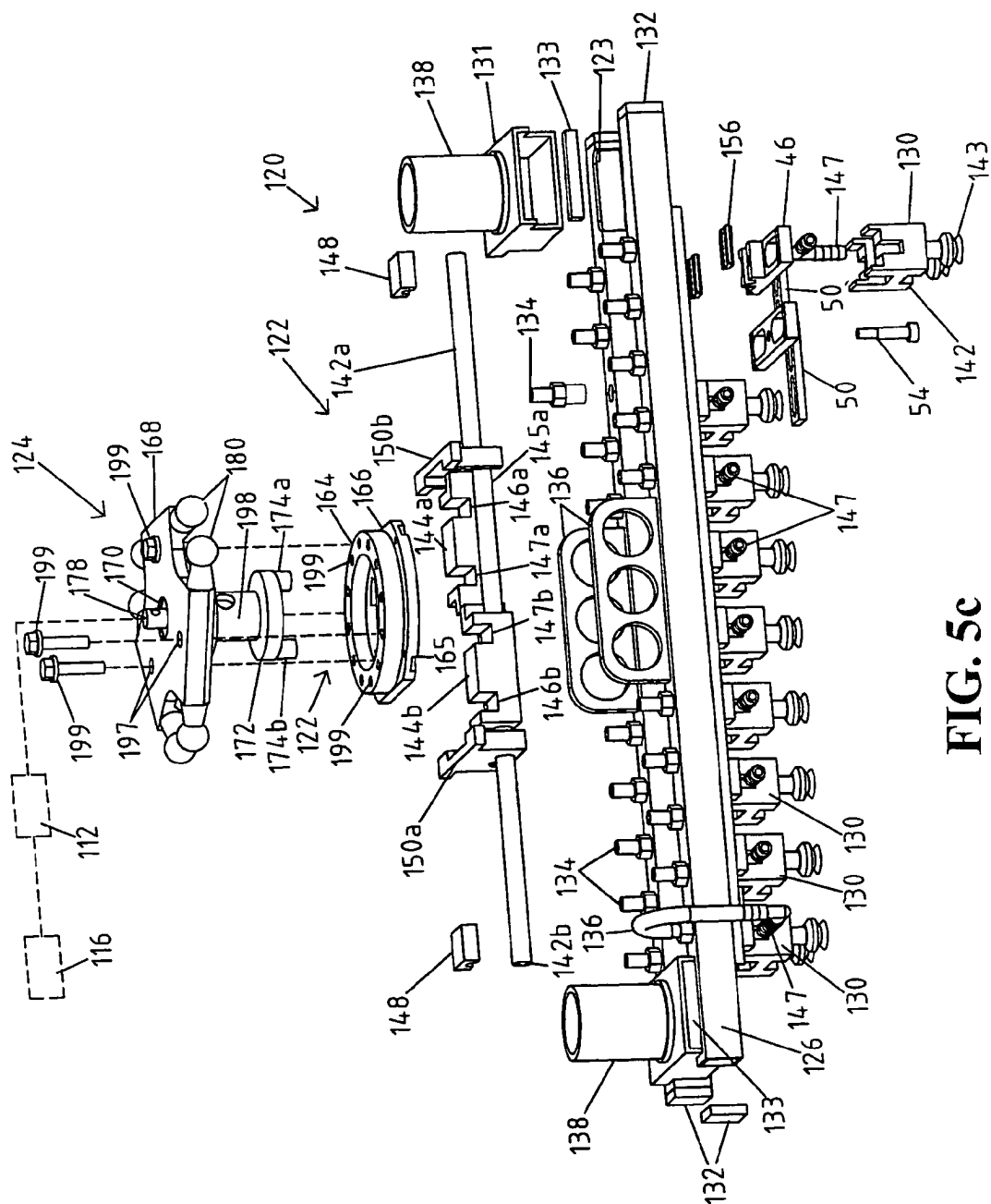


FIG. 5c

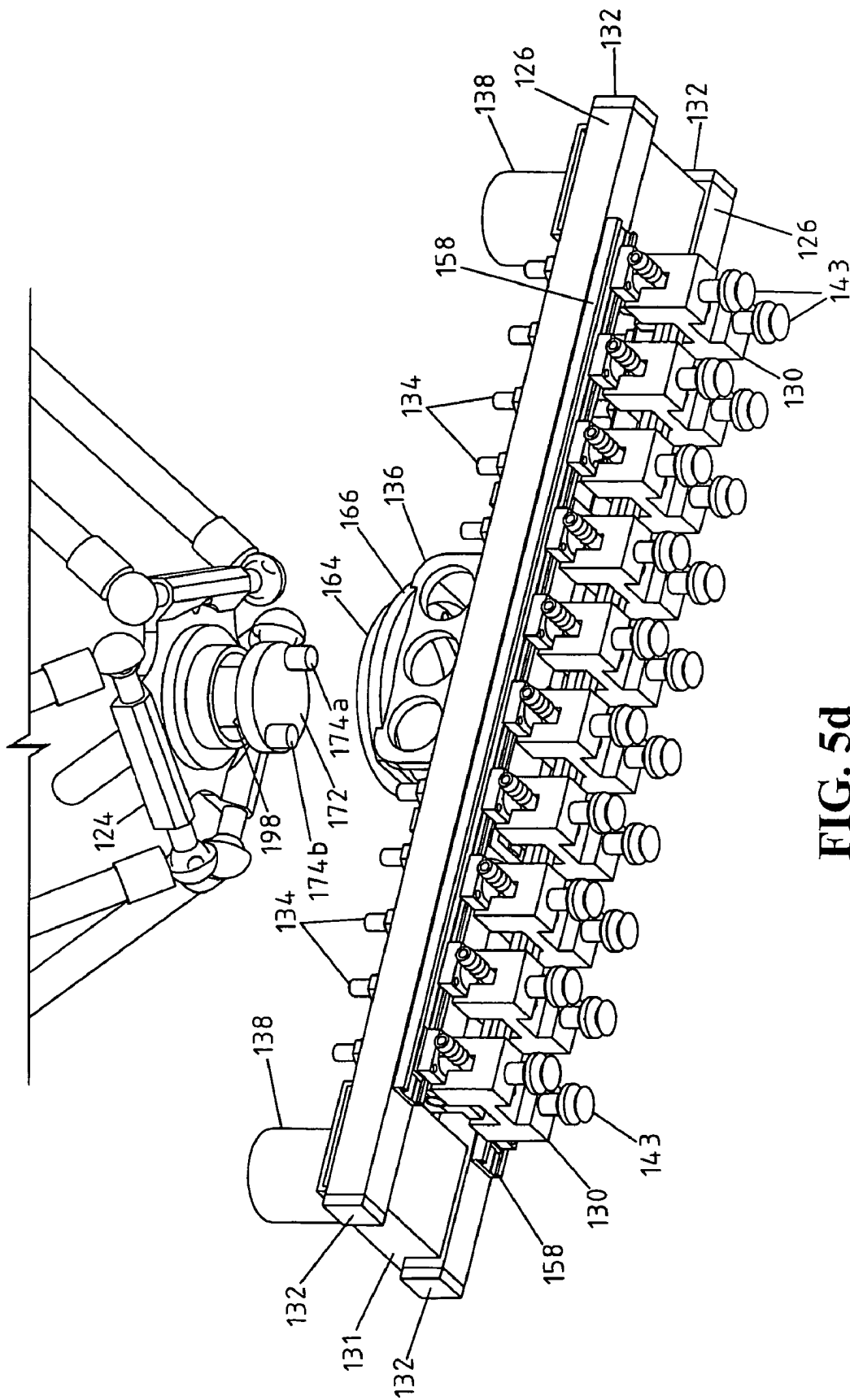
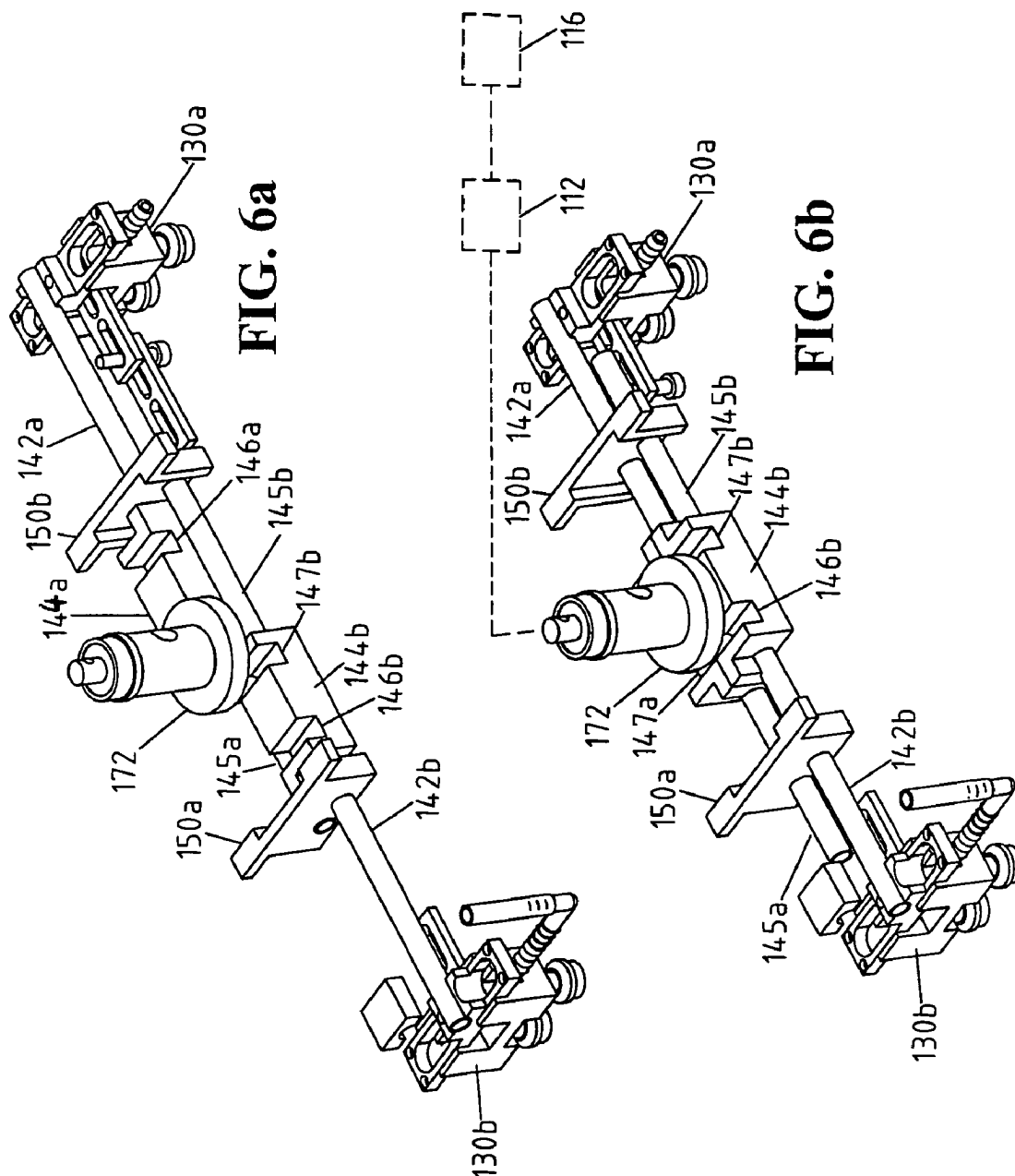
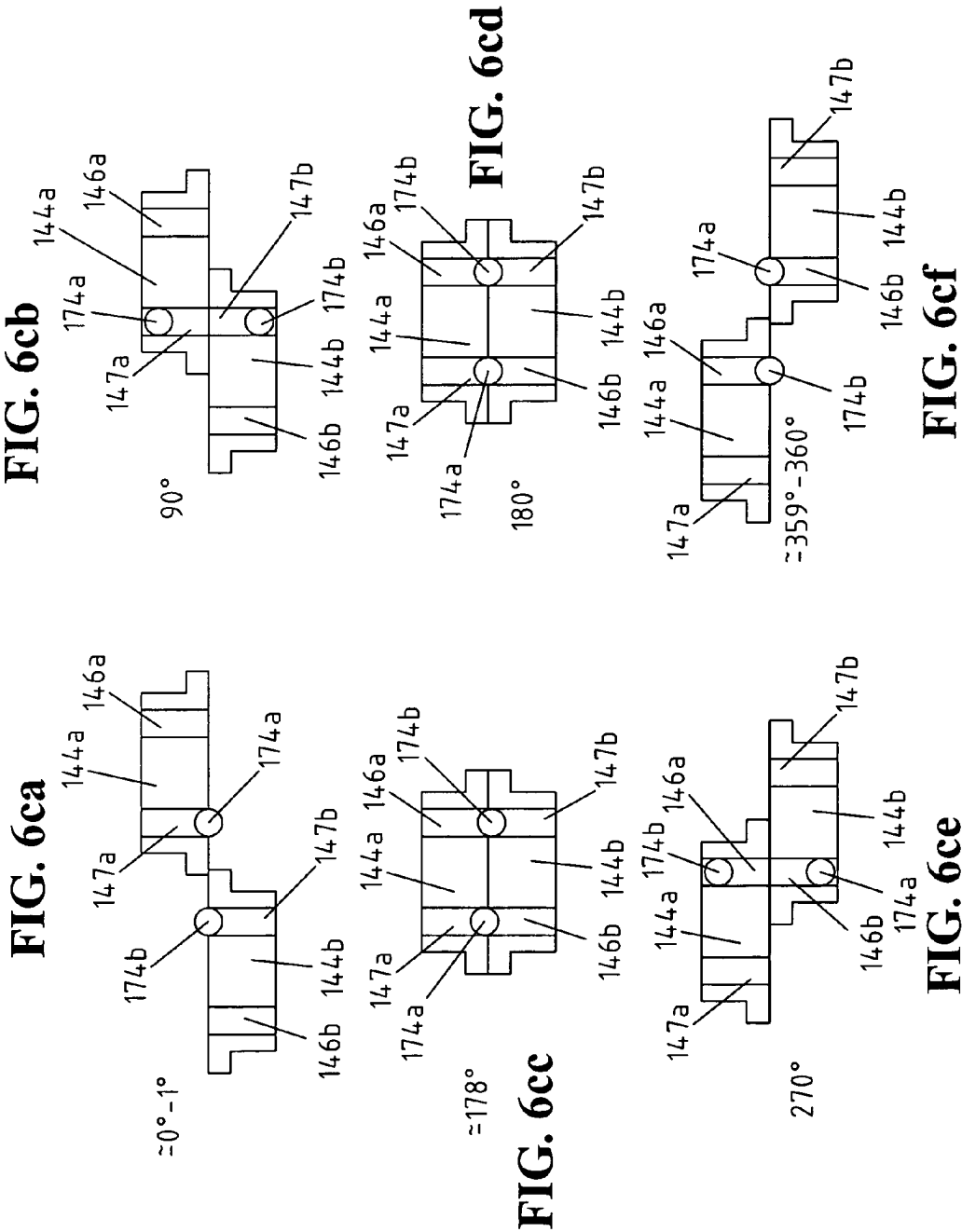


FIG. 5d





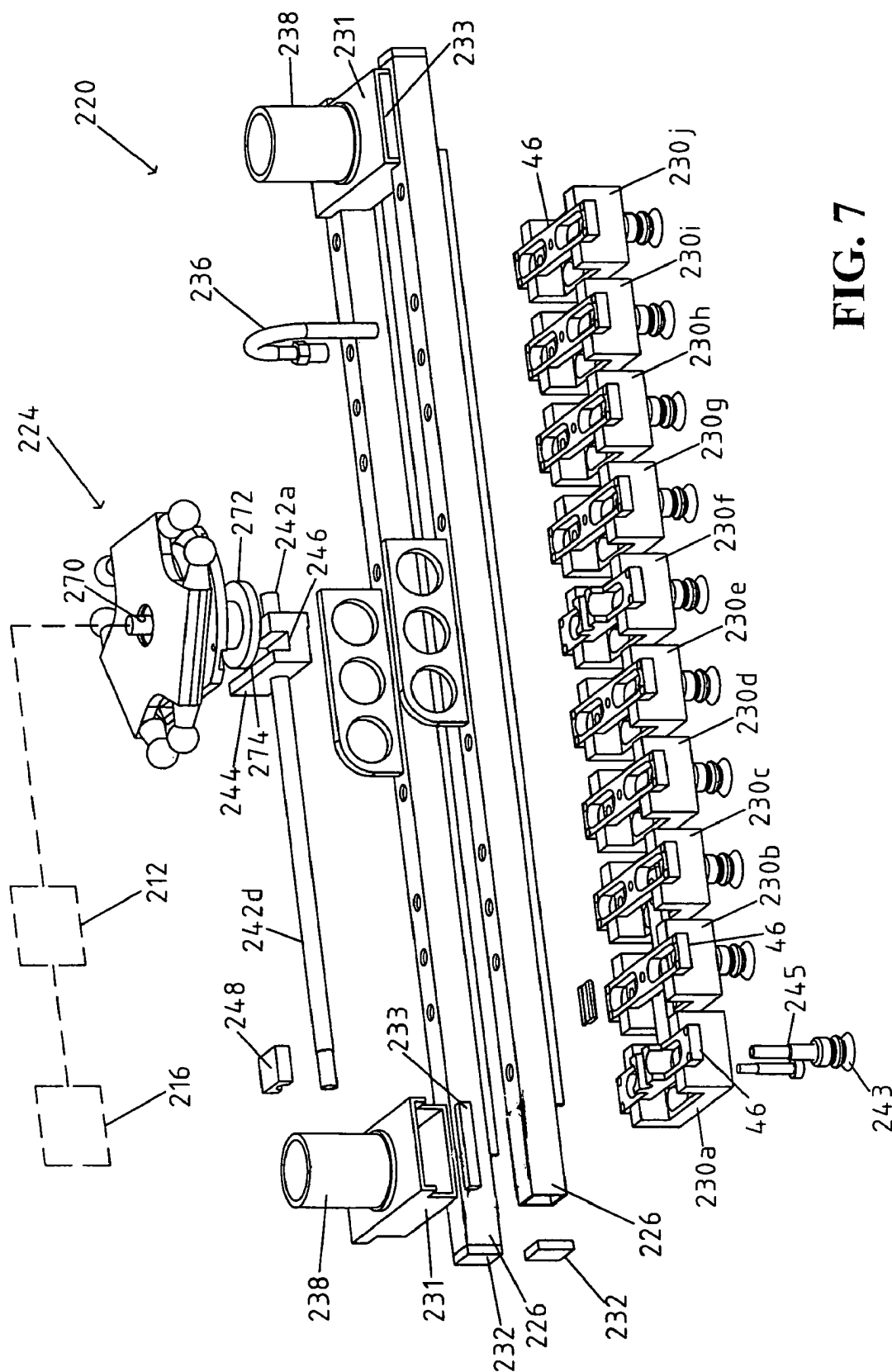


FIG. 7

FIG. 8a

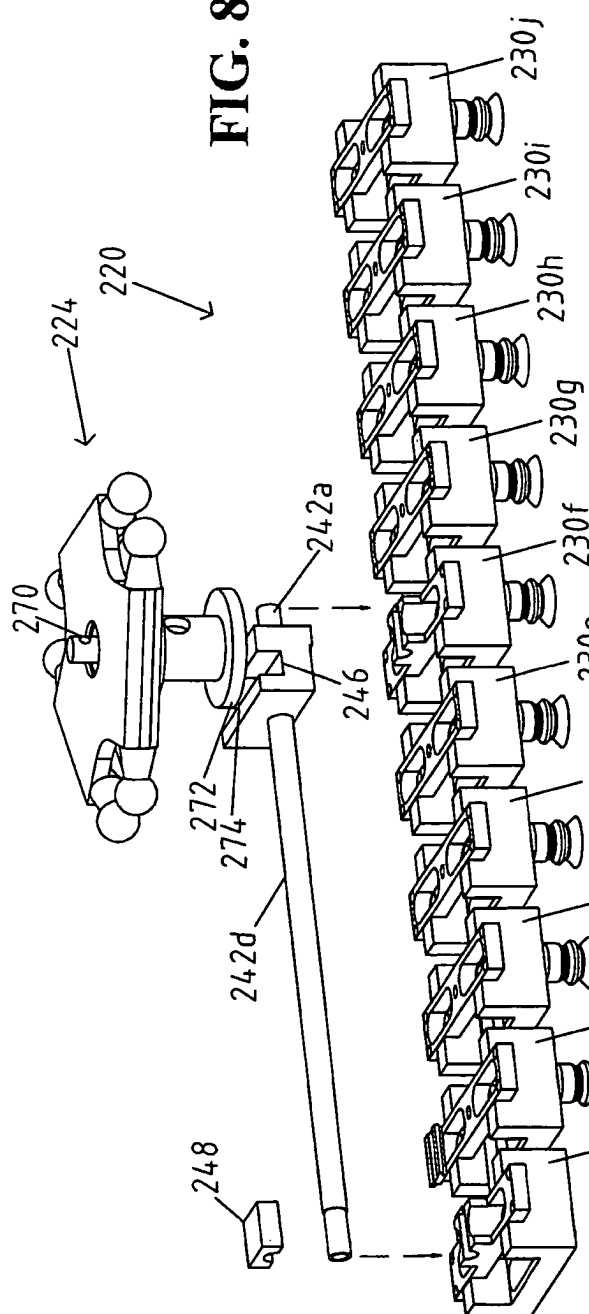
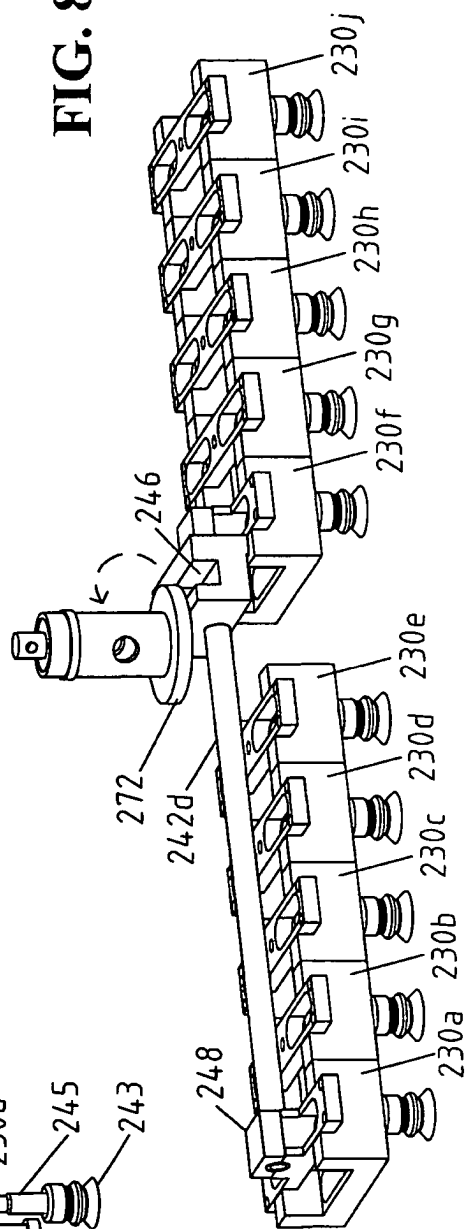


FIG. 8b



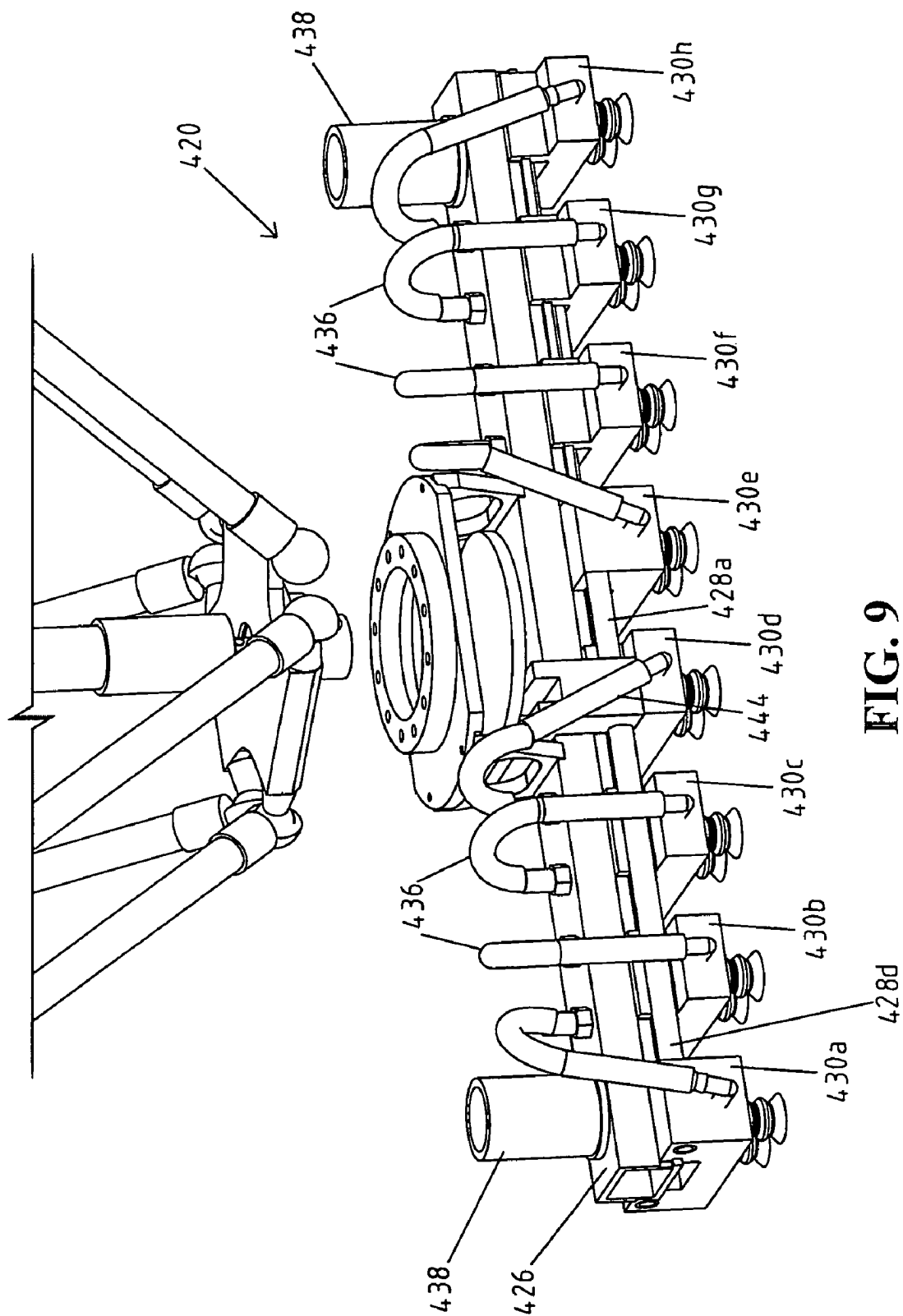


FIG. 9

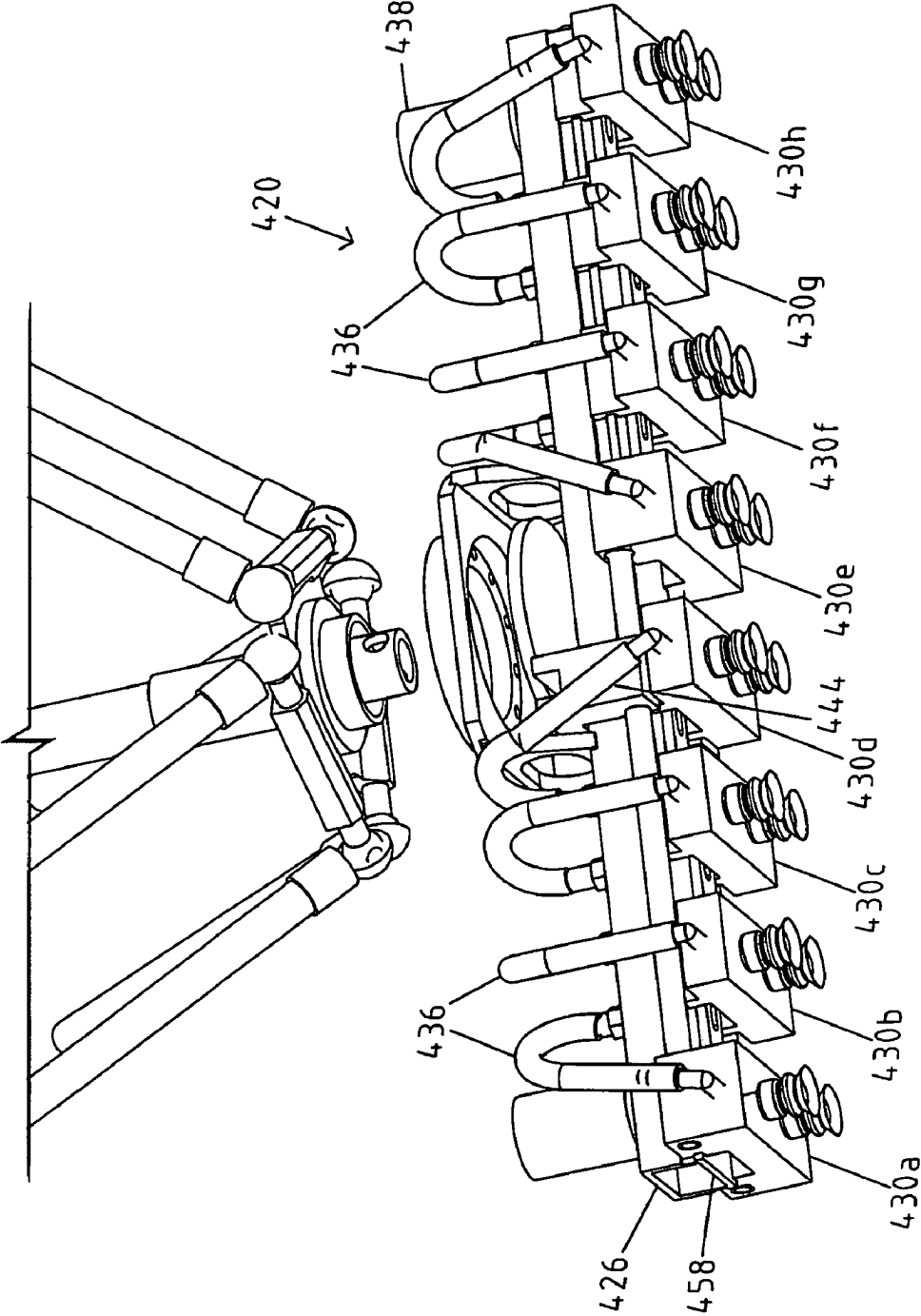


FIG. 10

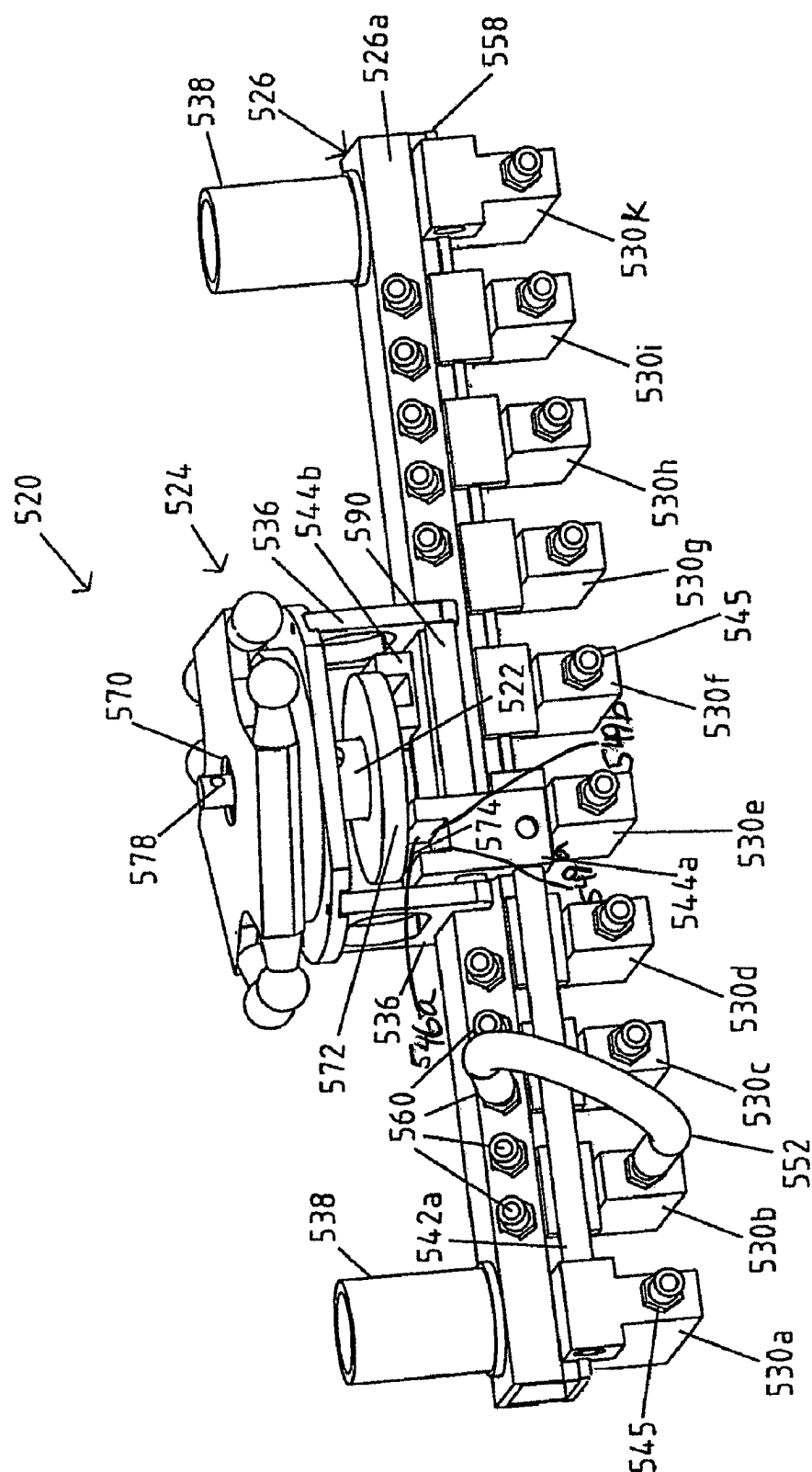


FIG. 11

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END EFFECTOR WITH MULTIPLE PICK-UP MEMBERS**CROSS REFERENCE TO RELATED APPLICATIONS**

This is a continuation application of U.S. patent application Ser. No. 10/420,075 filed Apr. 22, 2003, which is related to U.S. Provisional patent application Ser. No. 60/374,408 filed Apr. 22, 2002, the entire contents of both applications being hereby incorporated herein by reference.

FIELD OF THE INVENTION

The present invention relates to end-effectors for use with devices such as robotic arms.

BACKGROUND OF THE INVENTION

End-effectors attached to devices such as robotic arms are well known. These end-effectors often have operational members that perform operations on items. One common type of operational members are pick-up members which can be used to pick up, move and release items.

The use of devices as such as robotic arms with end effectors, that can perform operations on items, is also well known in various industries, such as for example, in the packaging industry. Such robotic arms use a variety of end effectors, for example, to move items from an article feed conveyor into open receptacles such as for example, cardboard boxes. Advantageously, robotic arms and their end-effectors can be moved through a wide range of orientations and positions in a three-dimensional space. One example of the use of a robotic arm and end effector to package items is disclosed in U.S. Pat. No. 5,060,455 ("Robotic Case Packaging System and Method"), the contents of which are hereby incorporated by reference.

Robotic arms are traditionally constructed as a cascade of several joined sections, each of which can be rotated and translated in a three-dimensional space so as to achieve a desired position of the end section of the robotic arm, and thus achieve a desired position and orientation in the three-dimensional space for the end effector attached to the end section of the robotic arm. Disadvantageously, because several different sections of traditional robotic arms have to be separately controlled, such robotic arms are very slow, and therefore not particularly well suited for use with high rate packaging systems. However, a more recent robotic arm that can move at very high speeds is the robotic arm disclosed in U.S. Pat. No. 4,976,582 ("Device for the Movement and Positioning of an Element in Space"), the contents of which are hereby incorporated by reference. This robotic arm, sometimes referred to as a "Delta" robot or a "Spider" robot uses three independent and non-joined control arms extending from a base element and attached to a movable element to position and orient the movable element in three-dimensional space. An end effector is attached to the movable element. Preferably, the end effector can be rotated about its center by connecting a rotatable shaft that is connected to a motor preferably positioned at the base element of the Delta robot. Advantageously, this design allows the movable element to be moved at accelerations ranging between 12 G to 50 G.

Because of the high speeds at which Delta robots can move, Delta robots have been used in industry to package items. For example, a packaging system manufactured by SIG Demarex uses a Delta robot to package various food items. This packaging system uses an end effector comprising of six

2

pick-up members to simultaneously pick-up six items. Gripping of the items in the packaging system is usually achieved by suction cups on the end effector which grip one or more items. The suction is applied to the cups through the use of a vacuum system. Once the end effector attached to the movable element in the Delta robot has picked up the items, the end effector is moved to a position proximate a receptacle at some desired position relative to the rest of the packaging system. At this release position the items can be deposited into the receptacle.

Advantageously, the positions of the pick-up members on the end effector can be adjusted so that the pick-up members can pick-up several items at the same time, that are far apart from each other. Subsequently the items held by the end-effector can be converged, by moving the pick-up members toward each other, thus bringing the items closer to each other. Having adjusted the spacing of the items, they can be deposited into a single receptacle in a more closely packed configuration.

Known designs of end effectors for simultaneous transport of a number of items use pneumatic rods, or equivalent actuation mechanism, that are attached to each one of the pick-up members on the end effector to control the positions of those pick-up members on the end effector. One of the main problems with such end effector designs is the high complexity involved in individually controlling the position of the pick-up members. Additionally, the physical size of each actuation device places constraints on the maximum number of actuation devices that can be combined to form the actuation mechanism of an end effector.

Another problem with the use of Delta robots to package items is the limitation of the load weight that can be carried by the end effector due to the high speeds at which the movable element, and the end effector attached to it, move. A heavy weight load would necessarily reduce the maximum acceleration that can be obtained for the movable element and the end effector. Thus, one of the important considerations in the design and use of an end effector is the weight of the end effector. The lower the weight of the end effector, the more weight that can then be picked-up by the end effector for transport to a receptacle. With current designs of end effectors for simultaneous transport of multiple items, the use of separate pneumatic rods to control individual pick-up member adds considerable weight to the overall weight of the end effector. This reduces the total weight that can be picked-up by the end effector for transporting an article to a receptacle.

It would therefore be desirable to have a lighter weight end effector, that uses a less complex and cumbersome actuation mechanism to control the positions of the pick-up members on the end effector.

It is also desirable to be able have an end effector which can perform a first operation on a group of several items spaced at a first pitch and then group those items into at least two groups, each item in the two groups being at a second pitch, and perform a second operation on the items in both groups at the same time.

SUMMARY OF INVENTION

It is therefore desirable to provide for an end effector consisting of multiple pick-up members for transporting items from one location to another location, which uses a simple actuation mechanism to control the positions of the pick-up members on the end effector. It is also desired to be able to economize on the weight requirements of the actuation

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mechanism of the end effector so as to allow the end effector to pick-up and transport a larger number of items at high speeds.

In one aspect of the invention there is provided an end effector for use with a moving device, the end effector comprising: a) a frame; b) a plurality of operational members mounted for movement on the frame; c) an actuation mechanism directly connected to a first operational member of the plurality of operational members and operable to move the first operational member from a first position to a second position, and from the second position to the first position; (d) a linking apparatus for linking the first operational member to a second operational member of the plurality of operational members; wherein when the actuation mechanism moves the first operational member from the first position to the second position, the second operational member is moved by the linking apparatus from a third position to a fourth position, and when said, actuation mechanism moves said first operational member from said second position to said first position, said second operational member is moved from said fourth position to said third position.

In yet another aspect of the invention there is provided a method for lifting and transferring items from a first location to a receptacle using an end effector attached to a robot, said method comprising: a) moving said robot to position said end effector above a first batch of said items; b) actuating one of a plurality of pick-up members slidably mounted on the body of said end effector to a position directly above a first item of said first batch of said items, and using linking means connecting the remainder of said pick-up members to said one pick-up member to pull said remainder of said pick-up members to a position directly above the remainder of said first batch of said items; c) lowering said end effector so that said pick-up members can pick up said first batch of said items; d) raising said end effector; e) moving said robot to reposition said end effector above a receptacle; f) moving said one pick-up members to a converged position, and causing said remainder of said pick-up members connected to said actuated members to converge said pick up members using said linking apparatus; g) lowering said end effector toward said receptacles so that said first batch of said items are placed inside said receptacle; h) releasing said first batch of said items from said pick-up members; i) raising said end effector from above said receptacle; and j) repeating steps a-i to transfer the next batch of said items into a different receptacle.

In another aspect of the invention there is a method of carrying out operations on a plurality of items delivered at a first pitch, said method comprising: i) performing a first operation on a plurality of items, each said first operation carried out by one of a plurality of operational member spaced at a said first pitch; ii) moving said operational members to a second pitch by moving one of said plurality of operational members with an actuating mechanism, said remaining plurality of said operational members being interconnected to said one operational member; iii) performing a second operation on said plurality of items, each said second operation carried out by an operational member spaced at a second pitch.

In yet another aspect of the invention there is provided a method of carrying out operations on a plurality of items delivered at a first pitch, said method comprising: i) performing a first operation on a plurality of items, each said first operation carried out by one of a plurality of operational member spaced at a said first pitch; ii) moving said plurality of operational members to a second pitch and dividing said plurality of operational members into at least two groups; iii)

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performing a second operation on said plurality of items, each said second operation carried out by an operational member spaced at a second pitch.

In another aspect of the invention there is provided an end effector for use with a moving device, the end effector comprising: a) a frame having a longitudinally elongated portion; b) a plurality of operational members mounted to the elongated portion for longitudinal movement on the elongated portion; c) an actuation mechanism mounted to the frame and directly connected to a first operational member of the plurality of operational members and operable to move the first operational member longitudinally from a first position to a second position, and from the second position to the first position; d) a linking apparatus for linking longitudinally the first operational member to a second operational member of the plurality of operational members; wherein when the actuation mechanism moves the first operational member longitudinally from the first position to the second position, the second operational member is moved longitudinally by the linking apparatus from a third position to a fourth position.

In yet another aspect of the invention there is provided a robot having a robot arm with an end effector, the end effector comprising: a) a frame having a longitudinally elongated portion; b) a plurality of operational members mounted to the elongated portion for longitudinal movement on the elongated portion; c) an actuation mechanism mounted to the frame and directly connected to a first operational member of the plurality of operational members and operable to move the first operational member longitudinally from a first position to a second position, and from the second position to the first position; d) a linking apparatus for linking longitudinally the first operational member to a second operational member of the plurality of operational members; wherein when the actuation mechanism moves the first operational member longitudinally from the first position to the second position, the second operational member is moved longitudinally by the linking apparatus from a third position to a fourth position.

BRIEF DESCRIPTION OF THE DRAWINGS

In drawings illustrating by way of example only, embodiments of the invention:

FIG. 1a is a top view of a first embodiment of the end effector of the present invention with some parts omitted for clarity;

FIG. 1b is a front elevation view in cross section at 1b-1b in FIG. 1a;

FIG. 1c is a side elevation view in cross section at 1c-1c in FIG. 1a;

FIG. 1d is a top perspective view of the end effector of FIG. 1a, from one side;

FIG. 2 is an exploded perspective view of part of the end effector of FIG. 1a;

FIG. 3a is a bottom perspective view of the end effector of FIG. 1a in a diverged configuration;

FIG. 3b is a bottom perspective view of the end effector of FIG. 1a in a converged configuration;

FIG. 4 is a bottom plan view of the end effector of FIG. 1a, with pick up members removed for clarity, showing the linkage of the pick-up members;

FIG. 5a is top perspective view of an end effector in accordance with a second embodiment of the invention;

FIG. 5b is a bottom perspective view of the end effector of FIG. 5a;

FIG. 5c is an exploded view of the end effector of FIG. 5a;

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FIG. 5*d* is a view similar to FIG. 5*b* showing the mounting of the cam disc;

FIGS. 6*a* and 6*b* are top perspective views of parts of the end effector of FIGS. 5*a*-5*c*, which illustrate the actuation apparatus for the pick up members of the end effector of FIGS. 5*a*-5*c*;

FIGS. 6*ca* to 6*cf* (collectively "FIG. 6*c*") is a schematic view showing the sequence of operation of parts of the end effector of FIGS. 5*a*-5*c*;

FIG. 7 is an exploded view of an end effector constructed in accordance with a third embodiment of the invention;

FIGS. 8*a* and 8*b* are top perspective views of parts of the end effector of FIG. 7, which illustrate the actuation apparatus for the pick up members of the end effector of FIG. 7;

FIG. 9 is top perspective view of an end effector in accordance with a fourth embodiment of the invention;

FIG. 10 is a bottom perspective view of the end effector of FIG. 9;

FIG. 11 is top perspective view of an end effector in accordance with a fourth embodiment of the invention

DETAILED DESCRIPTION

With reference to FIGS. 1*a*-1*d*, 2, 3*a* and 3*b*, and FIG. 4, an end effector generally designated 20 is illustrated. Although not shown as such in these Figures, in use end effector 20 is secured to a moving device such as the end of a robotic arm. End effector 20 is formed with a frame structure, to which a plurality of pick up members 30 are movably attached. In this embodiment, the frame is made from two, spaced apart hollow rectangular pipe members 26 secured in a rigid, longitudinally parallel relation to each other by a main medial hub assembly 22. The pipes 26 and hub assembly 22 may in some embodiments be made of a lightweight but durable material such as aluminum, or carbon fiber composites, fiberglass, similar light composites and the like. Each of pipes 26 is sealed at its ends with closed plugs (not shown) such that the only openings to the interior of the pipes are those openings which are connected to vacuum hoses, and a central opening to the main vacuum manifold in the hub assembly, as will be described hereinafter.

The overall path of vacuum air flow through end effector 20 is from the suction cups 43, through the carrier members, into hoses 52, into and through one of pipes 26, and then through the passageway formed in hub assembly 22 to the external vacuum source.

As shown in FIGS. 1*a* and 2, positioned longitudinally along the top face of each of the pipes 26 are holes or apertures 32. Holes 32 are preferably positioned at equal distances from each other. As shown by way of example in FIG. 2, a hollow pipe connector plug 60 is fitted at one end into each of the holes 32. In some embodiments, the pipe plugs 60 may be made of materials such as a plastic, suitable nylon, or other suitable materials. The pipe connector plugs 60 are connected at their other ends to flexible hoses 52. Flexible hoses 52 may in some embodiments be made of a flexible material such as a suitable rubber or nylon.

FIG. 2 provides an exploded top perspective view of parts of an end effector 20 showing only one of the two pipes 26. As can be seen clearly in FIGS. 1*c* and 2, attached to the bottom face of each pipe 26 is a longitudinally extending guide rail 58. Each of the pick-up members 30 used to lift items from a conveyor belt or some other location in the packaging system are mounted on guide rails 58 and can slide along them. Each guide rail 58 is preferably shaped as a rectangular track with a narrow slot in its bottom face. Rail 58 extends across substantially the entire length of the bottom face of pipe 26. Each

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guide rail 58 may in some embodiments also be made of a light but durable metal material or alloy, such as aluminum.

Each of pick-up members 30 used to lift the items to be packaged is suspended from the rails 58 through the slot by rectangular plate members 48 that can slide along the inside of guide rails 58. The plate members 48 can be comprised of different components but include sliding portions that engage the rails that are preferably made from a material that facilitates easy sliding of the pick up member 30 in the rails 58, for example, materials such as polyethylene or teflon.

With reference in particular to FIGS. 1*b*, 2, 3*a* and 3*b* the hub assembly 22 is mounted with side plates 36 to and between pipes 26, proximate the middle of each pipe 26. Like the other components from which end effector 20 is assembled, side plates 36 are preferably made of light but durable materials such as aluminum. Side plates have apertures to reduce the weight. Side plates 36 can be mounted onto pipes 26 by using conventional techniques such as screws that are inserted into drilled holes 37 on side plates 36, which pass through the entire width of the side plates and fit into screw holes 38 (shown in FIG. 2) drilled onto the outside portion of pipe 26.

As shown in FIG. 2, the hub assembly 22, comprises a cylindrical pipe 63 (preferably also made from a durable but lightweight material such as an aluminum), that is connected to a manifold 61. The side openings of manifold 61 are sealed on either side with the side plates 36 which can be fastened therein or glued in place, or attached in other conventional ways. The bottom plate 69 of manifold 61 has opposed side openings 67 at the side edges of plate 69. Each opening 67 is mated with an opening 71 in the top face of a pipe 26 and abuts with side plates 36. Thus manifold 61 is sealed to pipes 26, with a substantially air tight seal such that air can flow from pipe 26 through openings 71 and 67 into manifold 61 and can then pass through pipe 63 to the vacuum source. A hose (not shown) connecting the vacuum source to pipe 63 can pass through a cylindrical slot 70 that passes completely through the movable connector member 24 that attaches the end effector 20 to the robot. In this way a vacuum can be applied to manifold 61 and pipes 26 to create a suction at suction cups.

The hub assembly is completed with a plate member 64 having an integrally formed flange 66. Flange 66 is secured with screws to the top edge of plates 36 side through screw holes 59 and 57 (FIG. 2). Once fastened to plates 36, plate member 64 contributes to the rigidity of the frame and provides a member to which movable connector member 24 of a moving device can be attached. In particular, in the embodiment of FIGS. 1*a*-3*b*, connector member 24 is configured for connecting end effector 20 to the arm (not shown) of a Delta robot such as the one manufactured by SIG Demarex and used in their Presto packaging system, or the Delta robot manufactured by ABB Flexible Automation company and used with their IRB 340 FlexPicker packaging system. It will, of course, be appreciated that connection plate 24 can be configured for connecting end effector 20 to other types of robots. In the preferred embodiment, connector member 24 comprises a 3-legged flange that has ball bearings 84 attached to each arm 68*a*, 68*b*, 68*c*. Connector member 24 can be secured to plate member 64 in a conventional manner such as by screws.

FIGS. 1*b*, 1*c*, 3*a* and 3*b* illustrate a plurality of pick-up members 30 associated with end effector 20. The pick-up members 30 are arranged serially along a central longitudinal axis Y of end effector 20 (FIG. 3*a*). As shown in FIGS. 1*a*, 1*b*, 2, 3*a* and 3*b*, every pick-up member 30 includes a carrier guide 40. It should be noted that in FIG. 2, the carrier guides (exploded away from pipe 26) are formed in an H-section that

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consists of a bridge section **44** and two side leg sections **42** that are attached to either end of the bridge section, and extend above and below the bridge section. Carrier guide **40** is also shown in (FIGS. **1c** and **1d**) formed as being of a generally inverted C-shape, having side legs that extend only upwards from the bridge section. The H-shape is more suitable when end effector is to be used for carrying heavier and/or larger items. Various other configurations are of course possible. Preferably, the carrier guide **40** is made of a suitable plastic material such as a high density polyethylene, a suitable composite material, or some other equivalent light but durable material. Inserted into a hole in the middle of the bridge section **44** of each H or C-shaped carrier guide **40** is a pin formed from a hex-head shoulder screw **54**. The screw **54** fastens the carrier guide **40** to a rectangular guide plate member **46**.

Attached to each of the side edges of guide plates **46** are plates **48**, each having outward extending flanges. Plates **48** are preferably made from a suitable plastic, and their flanges are received in the interior of guide rails **58**. The width of the flanges of plates **48** is larger than the width of the bottom slot of the guide rails or tracks **58** such that the plates **48** can slide longitudinally in the interior part of rails **58** along the length of the rails, but cannot fall off from or out of the guide rails. When mounted onto rails **58** by fitting the plates **48** into the interior section of guide rails **58** through the far ends of the rails, each guide plate **46** can slide along at least a portion of the length of the rails. Preferably, guide plate **46** is manufactured from durable materials such as aluminum, or possibly other durable materials that are relatively lightweight. In the preferred embodiment most of the surface area of guide plate **46** is occupied by two elliptically-shaped slots which flank the middle part of guide plate **46**. This configuration reduces the overall weight of guide plate **46**. The middle part of the plate **46** includes a threaded bore into which hex-head shoulder screw **54** is inserted to fasten the carrier **40** to the guide plate **46**.

In both the embodiment shown in FIG. **2** and the embodiment in FIGS. **1b**, **1c**, **3a** and **3b**, each carrier **40** has opposed upwardly extending leg sections **42**. Each leg section has a rectangular slot **41** passing vertically down to the base portion **44** of the leg **42** (as can be seen in the exploded view of FIG. **2**). A vertical bore is provided through leg section **42**, with an upper opening at the bottom portion of the channel **41**, and a lower opening at the bottom surface of leg section **42**. Attached proximate the bottom opening of each bore is a rubber suction cup **43** with a small opening at the peak of the cup. A hollow tube **45** is fitted into the opening of suction cup **43**. The tube **45** passes through the bore at the bottom of leg **42** and exits at the opening at the bottom part of slot **41**. Each of tubes **45** (one passing through each bore in each of legs **42**) is in turn attached to a flexible hose **62**, which, as explained above, is attached to a pipe plug **60**. The length of flexible hose **62** should not limit the extent to which a pick-up member **30** can move away from its respective pipe plug **60**. As previously described, the pipe plugs **60** connect the flexible hoses to the hollow pipes **26**, which in turn attach to hub **22** and an extraneous vacuum source (not shown). Thus, when the vacuum source is turned on, a suction force is created at suction cups **43** which causes items proximate cup **43** to be lifted and held by the suction cups.

To control and facilitate the movement of the pick-up members **30**, the pick-up members **30** that are mounted onto guide rails **58** are inter-connected to each other with an operational member interconnection mechanism. In the preferred embodiment of the present invention, a pick-up member **30** is connected to an adjacent pick-up member **30** by using an

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operational member interconnection mechanism comprising a tie link plate **50** as illustrated in FIGS. **2** and **4**. Tie link plate **50** is preferably a rectangular plate, made of a plastic such as polyethylene or some other light but durable material. Each pick up member **30** (except those pick up members at the end of the end effector) will be interconnected to a pick up member on each side with a link plate **50**. Each link plate **50** will have one or more slots which receive therethrough pin or rod **54** associated with each pick up member **30**. Each pin or rod **54** is preferably made of steel, or some other strong wear resistant and good shear strength material, and is preferably hollow so as to reduce the weight of the pin or rod. In the preferred embodiment, each tie link **50** actually has two equal longitudinally extending slots **51**, **53**, each slot for receiving one pin of one pick up member **30**.

A tie link plate **50** should be rigid enough that as a first pick-up member to which the tie link is connected is forced in an outward direction from the center of the end effector **20**, the second adjacent pick-up member **30** to which the tie link plate **50** is connected is pulled in the same direction. Tie links **50** are preferably formed by extruding the plastic, or some other material that meets the required criteria, through a mould bearing the shape of a tie link **50**. Those skilled in the art will of course realize that a tie link **60** may be manufactured by other manufacturing processes. The length of the slots **51**, **53** in a tie link **50** controls the extent to which adjacent pick-up members **30** can be separated from each other. Generally, the larger the length of each slot, the farther the possible separation that is possible between the pins and their respective pick up members.

Other tie links can also provide the desired functionality. For example, a tie link can be provided with only a single slot receiving two pin members. The tie link could also be constructed in other ways such as with springs or rubber bands.

In the illustrated preferred embodiment, to link adjacent pick-up members, one slot of a tie link **50** is placed around the hex-head shoulder screw **54** of one pick-up member **30**, while the other slot is placed around the hex-head shoulder screw **54** of the adjacent pick-up member **30**. It will be apparent, that with the exception of the pick-up members **30** that are located at the far ends of the end effector assembly, two tie links are placed around every hex-head shoulder screw, with each tie link **50** connecting a pick-up member **30** to the pick-up members **30** on one of its two sides. As shown in FIG. **4**, the tie links **50** are arranged in overlapping relationship. Once the tie links **50** are placed on the hex-head shoulder screws **54** of the pick-up members, the screws **54** can be fastened to the guide plate **46**. As shown in FIG. **1c**, the tie links **50** are held above bridge sections **44** and below guide plates **46** between leg sections **42**.

Thus, a chain of pick-up members **30** can be mounted onto guide rails **58** by placing the plates **48**, corresponding to one pick-up member **30**, through the opening at the side of guide rails **58**, sliding the pick-up member **30** along the rails, and repeating the same for the other pick-up members **30**. Once pick up members **30** are mounted on the rails, the end of the rails **58** could be sealed.

Control of the movement of the pick-up members **30** is achieved by controlling the movement of one, or more, pick-up member **30** using an actuation mechanism. Since all the pick-up members are interconnected to each other through a chain of tie links **50**, moving one leading pick-up member **30** in a chain can cause the movement of other following pick-up members as well. In the preferred embodiment of FIGS. **1a-4**, two double acting pneumatic cylinders **28a** and **28b** are used to directly alter the positions of the pick-up members **30** at the ends of the end effector **20**. As best shown in FIG. **1d** cylinder

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28a (which is mounted and constructed identically to cylinder **28b**) is connected to a compressed air source (not shown) through pipes connected to fittings **79** and **81**. A bulkhead member **80** is fixedly attached to, and depends down from hub assembly **22**. Cylinder **28a** is mounted between bulkhead member **80** and pick up member **30a** located at one end of end effector **30**.

In one embodiment, industry standard double acting pneumatic cylinders, such as those manufactured by Festo, are used. As will be appreciated by the person skilled in the art, in a double acting pneumatic cylinder, the piston in the cylinder can be pushed in two opposite directions, thereby allowing for the actuating rod attached to the piston to be either extended or retracted. Cylinder **28a** can have its rod **31a** extend by forcing compressed air into fitting **81** and venting fitting **79**. Rod **31b** can be retracted by venting fitting **81** and applying compressed air to fitting **79**. Compressed air is applied to fittings **79** and **81** with hoses (not shown), and venting takes place in known ways which can for example include a controller and valves, which can be integrated with the overall control of the moving device.

Additionally it will be appreciated that cylinders **28a** and **28b** can be controlled by for example a Programmable Logic Controller ("PLC") (not shown) so that they work in unison. Therefore, they can have their rods **31a**, **31b** extended and retracted at the same time.

The actuating rods **31a** and **31b** of pneumatic cylinders **28a** and **28b** pass in a longitudinally extending channel **33** (see FIG. 1c) above the carrier guides **46** of the pick up members. As shown in FIG. 2, the actuating rod **31a** of one pneumatic cylinder is fastened to plate **46** of pick-up member **30a** using a clamp **29** and screws or bolts. The pneumatic cylinder **28a** and its rod **31a** are aligned so that the length of the cylinder **28a** and rod **31a** are oriented parallel to the length of pipes **26**.

In operation, the items that are to be packaged are positioned on a conveyor belt system or some other platform forming part of a packaging system. In the preferred embodiment, the end effector **20** is attached to a Delta robot. Optionally, the Delta robot may also include a sensory system, familiar to those versed in robotics, to determine the exact locations of the items to be picked up and moved, and the distances separating them, so that the end effector **20** can be positioned accordingly. It will however be typical for products only to be either picked up or dropped off when the carrier members **30** are either fully diverged or fully converged.

The control system of the Delta robot (not shown) positions the end effector **20** attached to moving member **24** above the items to be picked-up. Positioning of the end effector above the items to be picked-up is done in ways known to those familiar in the art of automated and robotic system control. The control system controlling the operation of the pneumatic cylinders **28a** and **28b** then releases compressed air that causes the pistons of the pneumatic cylinders **28a** and **28b**, to extend the actuating rods **31a** and **31b** to a desired position, so that the pick-up members **30** are situated above the items to be picked-up. The control system of the robot also will position the end effector as a whole (i.e. move the frame) to the correct position. Control of the pneumatic cylinders **28a** and **28b** and the extension of the actuating rods is done in ways known to those versed in the art of pneumatic cylinder control, such as by having valve operation controlled by a PLC or the robots controller.

With reference to FIG. 4, the actuation of the pick-up members **30** attached to pneumatic cylinders is shown. When the actuating rod **31a** attached to the pneumatic cylinders **28a** is extended, the pick-up member **30a** at the far end of one side

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of the end effector is extended outwardly and away from the center of the end effector. The hex-head shoulder screws **54a** of the far end pick-up member **30a** starts moving outwardly in the slot **51a** of the tie link **50a** in which the screw **54a** is placed until it starts pressing against the outer side of the opening **51a** in tie link **50a**. This in turn causes the tie link **50a** to be pushed outwardly, thus causing the side edge of opening **53a** in tie links **50a** to push against the hex-head shoulder screws **54b** of the adjacent pick-up member **30b**. This causes pick-up member **30b** to also be pulled outwardly and away from the center hub assembly **22** of end effector **20**. The other pick-up members **30** inter-linked to pick-up member **30a** will also be pulled outwardly and away from the center of the end effector **20**. Similarly, the same effect is achieved on the other side of the hub assembly **22** when actuating rod **31b** attached to the piston of pneumatic cylinder **28b** extends outwardly, but in a direction opposite that in which the actuating rod **31a** and pick-up member **30a** is moved. The result is that when the cylinders are fully extended, the pick up members **30** are configured as shown in FIG. 3a, with the pins (screws **54**) being positioned at the outer edges of the slots in tie links **50** (as shown in FIG. 4).

It will be appreciated that in this embodiment, if the actuating rods **31a** and **31b** are extended by less than their maximum extension, separation between the pick-up members **30** will be non-uniform since the partial extension of the pick-up members at the far ends of the end effector **20** may not be enough to cause the tie links **50** linked to the pick-up members closer to the center of the end effector to push those pick-up members outwardly. Therefore, where the actuating rods **31a** and **31b** are not fully extended, the pick-up members will be more closely clustered or spaced near the center of the end effector **20**.

Once the pick-up members **30** are positioned exactly above the items to be picked-up, the end effector is lowered so that the suction cups **43** attached to each carrier guide **40** of each pickup member **30** are brought into contact with the items to be picked-up. The vacuum source attached to the Delta robot will then be activated (if it has not already been activated) thereby creating a suction force at the suction cups **43**. This causes the items on a conveyor belt (not shown), or other platform on which the items are located, to be lifted off the conveyor belt, and held by the suction cups **43**.

The Delta robot next moves the moving member **24**, and the end effector **20** connected to it, in the direction of the receptacle where the items are to be deposited. The position and orientation of the end effector is controlled by the arm sections of the Delta robot. While the end effector **20** moves towards the destination receptacle, the actuating rods **31a** and **31b** can start retracting by having compressed air from the compressed air source applied to, and corresponding venting of the fittings of the pneumatic cylinders **28a** and **28b** so that the pistons are moved back into their retracted positions. This in turn causes the pick-up members **30** on either side of the central portion, to converge back toward the center of the end effector **20**, to the position shown in FIG. 3b. This enables the items carried by the end effector **20** to be deposited into the receptacle (not shown). The extent of the desired convergence of the pick-up members **30** will depend on the size of the receptacle into which the lifted items are to be deposited. A receptacle with a relatively small opening will require that the pick-up members **30** be more tightly converged.

The extent to which the cylinders can retract and compress pick up members **30**, will be determined by the movement of the rods, the configuration of the slots in the tie links **50**, and the physical size and shape of the pick up members themselves. It is usually desired that the **30** members be able to be

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compressed until they are in abutment with each other as shown in FIG. 3b, so that in fully converged position, the pins of the end effectors are not in abutment with the inside faces of the slots 51 and 53. However in other embodiments, the tie links themselves, and in particular the configuration of the slots 51 and 53, can be selected so that during the contraction, the tie links inner faces interact with the pins to push the members together and this determines the minimum separation of members 30.

Once the end effector 20 reaches a position directly above the destination receptacle, the end effector 20 is lowered into the receptacle. The suction force at suction cups 43, created by the vacuum source, is cut off, thereby releasing the items from the suction cups 43. The end effector is then raised, and the Delta robot can then move the end effector 20 to a position above the next batch of items to be packaged. The destination receptacle into which the items were deposited is, meanwhile, further processed by the packaging system.

One disadvantage of using pneumatic cylinders to actuate the position of the pick-up members is that pneumatic cylinders have non-linear behavior due to the use of compressed air as the means of controlling the position of the pistons in the cylinders. This leads to poor control of the speed and precise position of the pistons. Accordingly, in the second embodiment of the present invention an end effector is implemented with a more precise actuation mechanism (also referred to herein as an actuator).

With reference to FIGS. 5a, 5b and 5c an end effector 120 is shown, and which is constructed in a manner similar to end effector 20. End effector 120 comprises a frame that may consist of two hollow rectangular pipes 126 that are open at their far ends. Pipes 126 are configured in a parallel longitudinal arrangement. A pipe cap 132 is inserted into each of the openings at the far ends of the pipes, thus sealing the pipes 126 at their ends. Fitted into holes 121 located on the top surface of the pipes 126 along the main axis of the pipes 126 are connector pipe plugs 134. Connected to each pipe plug 134 is one end of a flexible hose 136 (for clarity in the figures, only one such hose 136 is shown, in FIG. 5c) made of flexible, and preferably resilient material, such as rubber.

Each hose 136 is attached at its opposite end to a hollow connector tube 147 (like tubes 45 in the previous embodiment). The tube 147 is received inside the bore on one of the legs 142 of an operational member such as a pick-up member 130. The pick-up members 130 used in this embodiment of the end effector of the present invention are substantially the same pick up member 30 as those described in relation to the first embodiment of the end effector. As will become apparent below, because the actuation mechanism used in conjunction with the second embodiment of the end effector is bulkier and occupies more space than the actuation mechanism used with the first embodiment of the end effector, it is more expedient to pass the flexible hoses 136 on the outer sides of the hollow pipes 126 than from the inner sides of the pipes. Furthermore, to allow for easy attachment of the flexible hoses 136 to hollow connector tubes 147, a generally C-shaped tube can be used.

A hose 136 also extends from a pipe plug 134 on the opposite, second hollow pipe 126, positioned across from the first pipe plug, and attaches to the hollow connector tube 145 received inside the bore on the other leg of the same pick-up member 130. Accordingly, every pick-up member 130 is attached to two with connectors 147 to two flexible hoses 136, one extending from each of the hollow pipes 126.

Each pipe 126 also consists of two inner side openings 123 located proximate to the ends of the pipes 126. Each opening extends inwardly from the middle of the top side of each pipe

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126 towards the center of the end effector down to the middle of the inner side of each pipe. The openings on one pipe 126 are positioned opposite and across from the openings on the other pipe 126.

Two hollow, generally T-shaped header manifold assemblies 131 are provided at opposite end of the pipes 126 in between the side openings 123 on each pipe 126, thereby completely covering and substantially sealing the openings 123 in the pipes 126. Manifold assemblies 133 have side plate members 133 which complete the side seals. A circular bore is provided in the top surface of each of the T-shaped header manifold assemblies 131, and a cylindrical pipe 138 is fitted into the bores. Connected to each of the cylindrical pipes 138 is one end of a hose (not shown), that is in turn connected at its other end to an extraneous vacuum source (not shown). The suction cups 143 on each of the pick-up members 130 are therefore interconnected to the vacuum source through the hollow tubes 145, which are connected to flexible hoses 136, that are connected to the pipe plugs 134, that are fitted into the hollow pipes 126 and which in turn are connected to the T-shaped manifold assemblies 131, that are connected to cylindrical pipes 138, which are in communication with the vacuum source. Consequently, when the vacuum source is turned on, a suction force is created at the suction cups 143, thereby lifting and holding items to be packaged when they are located proximate suction cups 143. Of course, it will be appreciated that a different gripping mechanism may be employed to lift and transfer the items to their destination receptacles instead of the vacuum based mechanism used in this embodiment.

Attached to the bottom of each pipe 126 is guide rail 158. As with end effector 20, each guide rail 158 of end effector 120 is preferably also a hollow rectangular pipe with a narrow opening at the bottom surface of the pipe extending longitudinally along the entire length of guide rail 158. Mounted on the guide rails 158 are pick-up members 130. The pick-up members 130 are linked to each other using the tie link 50 mechanism described above. Each tie link 50 links together two adjacent pick-up members 130 by placing the hex-head shoulder screw 54 of one of the pick-up members 130 through one slot of the tie link 50, and placing the hex-head shoulder screw of the adjacent pick-up member 130 through the other slot of the tie link. The chain of pick-up members 130 is then mounted onto guide rails 158 by fitting the plates 156 attached to the sliding carrier guide 46 of each of the pick-up members through the opening at the far ends of the guide rail 158, and sliding the pick-up members down the guide rails 158.

Mounted on the upper surface of each of pipe 126, at a medial position, is a side plate 136. Hub assembly 122, comprising of a cylindrical hub portion 164 and a flange 166, is then fastened to the side plates by using screws 165 to attach the flange 166 to top edges of side plates 136. Fitted within the cylindrical hub portion 164 of hub 122 and bearing mounted on robot connection member 124 of the robot, is a rotary cam device (also referred to simply as a rotary device) 172. Rotary cam device 172 may be a circular disc having moving elements that may in the form of cam followers 174a, 174b which interact with respective generally transversely oriented cam surfaces in cam slots (cam slots being also referred to herein as cam tracks) in cam devices such as cam blocks 144 to provide cam movement to effect the actuation of the pick-up members 130 of the end effector 120, and thus cause movement of the pick-up members 130 in a longitudinal direction relative to the frame.

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Pipes **126**, manifold assemblies **131**, side plates **136**, rotary cam disc **172**, hub portion **164** and flange plate **166** can all be made from lightweight but durable materials such as, for example, aluminum.

The cam followers **174a**, **174b** may be small knobs or pins positioned diametrically opposite to each other on disc **172** proximate the perimeter of the bottom surface of rotary cam **172**. As will become apparent below, the cam followers **174a**, **174b** engage the actuation mechanism portion of the end effector **120** and control the outward expansion or convergence of pick-up members **130**.

The rotary cam **172** can be bearing mounted to moving connector member **124** of a Delta robot using a cross nut or other conventional mounting mechanisms. Cam disc **172** is secured to the end of a shaft **198** that extends through a slot **170** in member **124**. Moving member **124**, much like moving member **24** of the first embodiment of the present invention, is the part of the Delta robot that moves about in a three-dimensional space. Moving member **124** comprises of a 3-legged shaped flange **168**, at the middle of which, is a threaded cylindrical slot **170**. A rotatable shaft (not shown) extending from the Delta robot is fitted into slot **170** and attaches to a shaft connector **178** which in turn is connected to shaft **198**. The rotatable shaft of the Delta robot is connected to a motor (not shown) that controls the rotation of the shaft. Thus, the combination of the rotatable shaft of the Delta robot, the shaft connector **178** and shaft **198** comprise a rotatable drive shaft and as will be evident from FIGS. **5a-5c**, and FIGS. **6a-6c**, the robot shaft and shaft can both rotate about a common shaft axis that is oriented generally orthogonally to both the transverse direction of the cam slots **146a**, **146b** and **147a**, **147b** and the direction of movement of the pick up members relative to the frame. Rotation of the robot's shaft thus causes shaft connector **178** to rotate. This causes shaft **198** to rotate and thus rotary cam **172** to rotate clockwise, or counter-clockwise so as to control the actuation of the pick-up members **130**.

To secure end effector **120** to the robot arm, screws **199** are used, passing through holes **197** in flange **168** to attach in holes **199** (typically only three are needed) of hub portion **166**. This connects hub assembly **122** to the underside of connector member **124**.

Hub assembly **122** (1) produces structured rigidity to the frame of the end effector (2) provides a securement mechanism for mounting effector **120** to the robot through attachment to connector member **124** and (3) provides rigidity to resist the forces imparted during rotating of cam disc **172** which moves cam blocks **144**.

The actuation mechanism portion **140** that interacts with the cam followers **174a**, **174b** comprises of two cam slider blocks **144a** and **144b**, each can be made of a plastic such as for example, polyethylene or of a comparable lightweight and durable material. Each cam block has two transversely oriented, spaced cam slots **146a**, **147a** and **146b**, **147b** that are formed in top surfaces of each of the cam blocks.

Extending from each side of each cam block **144a**, **144b** are rod members that comprise an example of a connection mechanism (also referred to simply as connectors) interconnecting the cam blocks with the pick up members. Thus cam block **144a** has rod **142a** extending longitudinally from one of its sides and which is clamped at its end to a pick-up member **130** using a clamp **148**. The pick-up member **130** to which the push rod **142a** is clamped is the pick-up members situated at the far end of the end effector. That is, push rod **142a** of cam block **144a** is attached to the far end pick-up member **130a** at one end of the end effector. Push rod **142a** at its other end is attached to a cam block **144a**. Attached to the other side of

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each of cam block **144a** is rod **145a**. Rod **145a** is not clamped to any pick-up member but is merely used to properly guide the movement of cam block **144a**, and to prevent the cam block **144a** from wobbling while being engaged by the rotary cam **172**.

Likewise, cam block **144b** has rod **142b** extending longitudinally from one of its sides (on the opposite side to rod **142a**) and which is clamped at its end to a pick-up member **130b** using another clamp **148**. The pick-up member **130** to which the rod **142b** is clamped is the pick-up members situated at the far end of the end effector, opposite to the pick up member to which rod **142a** is attached. Rod **142b** at its other end is attached to a cam block **144b**. Attached to the other side of cam block **144b** is rod **145b**. Rod **145b** is not clamped to any pick-up member but is merely used to properly guide the movement of cam block **144b**, and to prevent the cam block **144b** from wobbling while being engaged by the rotary cam **172**.

The cam blocks **144a**, **144b** and the rods attached to them are positioned between the two hollow pipes **126**. The actuation mechanism is secured to the hollow pipes **126** by using two plastic T-shaped bearing plates **150a** and **150b**. Each T-shaped bearing plate is fixed to the hollow pipes **126** by fastening the arms extending from the top of the bearing plate to the hollow pipes **126** using screws. Preferably, each T-shaped bearing plate is positioned on either side of the side plates **136**, between the side plates and the first set of pipe plugs **134** immediately next to the side plate. Each bearing plate **150a** and **150b** also consists of two apertures situated near the bottom of, and transversely spaced on the plate. As better seen in FIGS. **6a** and **6b**, rod **145a** of cam block **144a** passes through one hole in bearing plate **150a**, while push rod **142b** of cam block **144b** passes through the other adjacent hole in plate **150a**. Likewise, rod **145b** of cam block **144b** passes through one hole in bearing plate **150b**, while rod **142a** of cam block **144a** passes through the other adjacent hole in plate **150b**. This arrangement of two rods attached to every cam block and having the rods passing through holes in two bearing plates that are rigidly secured to the pipes **126** allows the cam blocks to maintain stability without wobbling. Additionally, block **144a**, can move longitudinally and pass by block **144b** in close or abutting relation thereto.

FIGS. **6a** and **6b** illustrate the operation of the actuation mechanism of the second embodiment of the end effector **120**. FIG. **6b** shows the two sliding cam blocks **144a** and **144b**, in their mid positions relative to the end effector. At that position, the two cam blocks are aligned so that the two blocks are at the same longitudinal position. Additionally, in the mid-point position the cam followers **174** are positioned inside the slots **146a** and **146b** of both cam blocks **144a** and **144b**, effectively straddling both cam blocks. As can be appreciated from the mid-position drawing of FIG. **6b**, the separation between the slots **146** and **147** of each cam block as measured from the interior walls of each slot has to be slightly smaller than the diameter of the rotary cam **172** so that the cam followers **174a**, **174b** could be properly placed inside the slots at the mid-point position.

Starting from the position shown in FIG. **6a**, the movement of cam followers **174a**, **174b** in the slots in the cam blocks **144a**, **144b** is shown in FIG. **6c**. As the rotary cam **172** begins to rotate counter clockwise from 0 degrees, one cam follower moves outward in slot **147a** of cam block **144a**, while the other cam follower moves outward in slot **147b** of cam block **144b**. As the rotary cam rotates, the cam follower inside slot **147b** of cam block **144b** exerts pressure on the wall of slot **147b**, thereby pushing cam block **144b** toward the center of the end effector. Consequently, pick-up member **130a**,

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clamped to rod **142b** of cam block **144b**, converges toward the center of end effector **120**. The same effect is achieved by the movement of cam block **144a** and rod **142a**, likewise converging the pick up member to which it is attached toward the center.

The movement of the cam followers and cam blocks continues as shown in FIGS. **6a-6c**, with the rotation of rotary disc **172** and the accompanying movement of the cam followers. When the cam followers reach the position shown in FIG. **6c** as 360 degrees the pick up members will be in their fully converged position.

By reversing the direction of rotation of the shaft to which the cam followers are attached, the pick up members to which rods **142a**, and **142b** are attached can be extended outward away from the central hub assembly. Since all the pick-up members **130** mounted on end effector **120** are inter-linked to each other by tie links **50**, at the fully extended position of the cam blocks **144a** and **144b**, all the other pick-up members mounted on end effector **120** will reach their fully extended position.

In operation, the control system controlling the Delta robot positions the end effector **120** coupled to the moving member **124** above the items that are to be packaged. Optionally, a sensory system may be used to determine the exact locations of the items on the conveyor belt or other platform on the packaging system, so that the end effector could be positioned accordingly. The rotary cam is then rotated clockwise to extend the far end pick-up members clamped to the pushing rods attached to each cam block, thereby extending the pick-up members linked or interlinked to the far end pick-up members through tie links **50**. The pick-up members **130** are extended until they are situated directly above the items that are to be packaged. Subsequently, the end effector **120** is lowered so that the suction cups **143** attached to the H-carrier guide of each of the pick-up members **130** touch the items to be picked-up. The vacuum source interconnected to the suction cups is turned on, thereby creating a suction force at the suction cups **143**, which causes the items to be packaged to be lifted and held by the suction cups.

The Delta robot next moves the end effector **120** in the direction of the receptacle where the items are to be deposited. The position of the end effector **120** is controlled by the non-jointed arm sections of the Delta robot, while the orientation of the end effector about the z-axis is controlled by the rotatable shaft of the Delta robot inserted into slot **170** on moving member **124**. Preferably, while the end effector is en-route to the receptacle, the control mechanism of rotary cam **172** begins to rotate the rotary cam counter-clockwise, thereby causing the push rods **142a** and **142b** of the respective cam blocks **144a** and **144b** to be retracted back to the center of the end effector. This in turn causes the pick-up members **130** to converge back to the center of the end effector, thereby allowing the picked-up items to be easily deposited into the destination receptacle.

Once the end effector **120** reaches a position directly above the receptacle, the end effector is lowered until the items are placed inside the destination receptacle. Subsequently, the vacuum source is cut off, thereby releasing the items from the grip of the suction cups **143**. The end effector is then raised above the top opening of the receptacles, and is repositioned by the Delta robot to pick-up the next batch of items.

It will be appreciated that the system could be used in an opposite configuration, whereby items are picked up at a first location in a close, converged arrangement. The items can then be diverged prior to delivery to a second location.

FIGS. **7**, **8a** and **8b** show a third embodiment of an end effector of the present invention, which enables the end effec-

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tor to pick up several items and then separate those items into discrete groups. This is accomplished by providing an end effector where the pick-up members mounted for moving items into discrete groups. Each group can then, for example, be simultaneously deposited into separate destination receptacles. This allows for more efficient and controlled packaging of the items. To provide an end effector with pick-up members that can divide items into discrete groups, a modified implementation of the actuation mechanism described in the second embodiment is employed, but the end effector is otherwise substantially the same as the end effector of FIGS. **5a-5c**.

End effector **220**, shown substantially dismantled in FIGS. **7** and **8a**, has spaced, pipe members **226** with end flange assemblies **231** secured thereto and vacuum connection tubes **238**. Carrier members **230a-230j** are mounted to rails attached to pipe members **226** as described above.

Unlike the actuation mechanism used in conjunction with the second embodiment, the actuation mechanism of the third embodiment of the end effector **220**, comprises of a single cam block **244**. Cam block **244** is a rectangular block, may in some embodiments be made of a suitable plastic such as for example, polyethylene, or another light but durable material, in which a single cam slot **246** is cut out of, or formed in, the top part of the block along the entire width of the block. The width of the slot preferably approximates the diameter of a circular cam follower **274** protruding from the bottom surface of rotary cam **272**. This allows the cam follower to fit inside the slot, and to press against the walls of the slot as soon as the rotary cam starts rotating clockwise or counter-clockwise, thereby pushing the cam block in either direction of the longitudinal axis of the end effector. Specifically, with reference to FIGS. **8a**, **8b**, when the carriers **230a-230j** are in the diverged position shown in FIG. **8a**, and then when rotary cam **272** is rotated clockwise, the cam follower presses against the wall on the right-hand side of the slot, and causes the cam block **244** to move to the right. On the other hand, when the rotary cam rotates counterclockwise, (or if the cam follower is rotated past 180 degrees) the cam follower **274** presses against the wall on the left-hand side of the slot **246**, and accordingly causes the cam block to move to the left.

It should be noted that in this embodiment the rotary cam **272** can be operated in only one direction (i.e. clockwise or counterclockwise) through the full 360° to achieve the full cycle of convergence-divergence-convergence or divergence-convergence-divergence of the carrier members.

A long push rod **242d** is positioned between pipes **226** and is attached to one side of the cam block. A short rod **242a** is also positioned between pipes **226** and attached on the other side of cam block **244**. Both rods **242a**, **242d** move in the same direction as cam block **244** moves. It should be noted that rotary cam **272**, used in conjunction with end effector **220**, consists of only one cam follower, in contrast to cam rotary **172** used in conjunction with end effector **120** which has two cam followers that each simultaneously engage one of the two cam blocks.

FIGS. **8a** and **8b** shows the implementation and operation of the third embodiment of the present invention whereby the ten pick-up members or carriers mounted on the end effector **220** can be separated into two groups, each consisting of five pick-up members. As can be seen in FIG. **8a** and **8b**, pick-up member **230a** is clamped to rod **242d**, while pick-up member **230f** is clamped to rod **242a**. To effect a separation of the pick-up members into two groups, pick-up member **230e** and pick-up member **230j** have to be fixed to the end effector, preferably by securing those two pick-up members to guide rails **158** or to the hollow pipes **226** using screws, in a manner

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described above. Pick-up members **230a-230e** are inter-linked to each other by placing tie links **50** around the hex-head shoulder screws of adjacent pick-up members, as described above. Pick-up member **230e**, however, is not linked to pick-up member **230f**. Similarly pick-up members **230f-230j** are inter-linked to each other using tie links **50**, in a manner as described above. As will be appreciated, fixing pick-up members **230e** and **230j** to the end effector also serves to constrain the maximum outwardly extension of rods **242d** and **242b**. Since pick-up member **230e** is inter-linked to pick-up member **230a**, pick-up member **230a** can only be moved to a maximum distance equivalent to the length permitted by 4 tie links **50** from pick-up member **230e**. Similarly, since pick-up member **230j** is inter-linked to pick-up member **230f**, pick-up member **230f** can only be moved to a distance equivalent to the length permitted by 4 tie links **50** from pick-up member **230j**.

As shown in FIG. **8a**, the pick-up members **230** are positioned in their expanded state. When the rotary cam **272** is subsequently rotated counter-clockwise, as is shown in FIG. **8b**, the cam block **244** is pushed to the right. Consequently, pushing rod **242d** starts moving to the right, pushing in the process the pick-up members **230a-230e** linked to it. However, because pick-up member **230e** is fixed to the end effector, pick-up members **230a-230e** converge to each other, thus forming a single group of five pick-up members **230a-230e**. Similarly, pushing rod **242a** is also pushed to the right, causing the pick-up member **230f**, to which the pushing rod **242a** is clamped, to also move to the right. In the process, pick-up members **230g-230i** are also pushed to the right. Because pick-up member **230j** is fixed to the frame of the end effector (such as to pipes **226**), the pick-up members **230f-230j** converge into a second group of pick-up members.

It will be appreciated that if it is desirable to separate the pick-up members into other size groups, for example five groups consisting each of two pick-up members, then it is necessary to clamp pick-up members **230a**, **230c**, **230e**, **230g**, and **230i** to one of pushing rods **242d** or **242a**, and fix pick-up members **230b**, **230d**, **230f**, **230h**, and **230j** to the frame of end effector **220** (such as pipes **226**).

In operation, the control system controlling the Delta robot positions the end effector **220** coupled to the moving member **224** above the items that are to be picked up. Optionally, a sensory system may be used to determine the exact locations of the items on the conveyor belt or other platform on the packaging system, so that the end effector could be positioned accordingly. The rotary cam **272** is then rotated clockwise to move the pick-up members into their expanded position shown in FIG. **8a**. Rotation of the rotary cam **272** is effected by a rotatable shaft (not shown) extending from the Delta robot and inserted into through aperture **270** on moving member **224**. The pick-up members **230a-230j** are extended until they are situated directly above the items that are to be picked-up. Subsequently, the end effector **220** is lowered so that the suction cups **243** attached to the C-carrier guide of each of the pick-up members **230a-230j** touch the items to be packaged. The extraneous vacuum source—interconnected to the suction cups **243** through the cylindrical pipes **238**, the hollow pipes **226**, the plug pipes **134**, the flexible hoses **236** and the hollow tubes **45**—is engaged, thereby creating a suction force at suction cups **243**, which causes the items to be lifted off and held by the suction cups.

The Delta robot next moves the end effector **220** in the direction of the destination receptacles where the items are to be deposited. The position of the end effector **220** is controlled by the non-jointed arm section of the Delta robot. Preferably, while the end effector is en-route to the destina-

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tion receptacles, the control mechanism of rotary cam **272** begins to rotate the rotary cam counter-clockwise, thereby causing the push rods **242a** and **242b** to move to the right. This in turn causes the pick-up members **230a-230e** to converge into one group of pick-up members, and converge pick-up members **230f-230j** into another group of pick-up members.

Once the end effector **220** reaches a position directly above the two destination receptacles, the end effector is lowered until the items lifted by one group of pick-up members are placed inside one destination receptacle, while the other items lifted by the other group of pick-up members are placed inside the other destination receptacle. Subsequently, the vacuum source is cut off, thereby releasing the articles from the grip of the suction cups **243**. The end effector is then raised above the top opening of the receptacles, and is repositioned by the Delta robot to pick-up the next batch of items to be packaged.

In FIGS. **9** and **10**, an end effector **420** that is a variation of the embodiment of FIGS. **7-8b** is shown, along with the arms from a robot arm. In this embodiment, an end effector **420** is constructed like end effector **220** but is made with only a single central pipe member **426**. Pipe member **426** has a single rail **458** extending along its lower face and a total of eight pick up members **430** with suction cups **423** are secured for sliding movement thereon. Vacuum is supplied through pipes **438** to sealed pipe **426**, through hoses **436** into carriers **430** and suction cups **423**. Pick up members **430a**, **430e**, **430f** and **430j** are configured like **230a**, **230e**, **230f** and **230j** in FIGS. **8a**, **8b** and are interconnected with carriers **430b**, **430c**, **430g**, **430i**, to effect movement that is the same as in that embodiment of FIGS. **8a** and **8b**. In the embodiment of FIGS. **9** and **10**, rods **428d**, and **428a** connected to cam block **444** are provided on both sides of pipe **426** to ensure free sliding of pick up members **430** on rails **458**.

Finally, another embodiment is shown in FIG. **11** in which an end effector generally designated **520** is illustrated. Although not shown in FIG. **11** in use end effector **520** is secured to a moving device such as the end of a robotic arm. End effector **520** is formed with a frame structure, to which a plurality of pick up members **530a-k** are movably attached as described above. In this embodiment, the frame is made from a single, hollow rectangular pipe member **526**. As with the other embodiments, the pipe **526** and hub assembly **622** are preferably made of a lightweight but durable material such as aluminum, or carbon fiber composites, or similar light composites. Pipe **526** is sealed at its ends with closed plugs (not shown) such that the only openings to the interior of the pipes are those openings which are connected to vacuum hoses with connectors **560**, and end pipes **538**.

The overall path of vacuum air flow through end effector **520** is from the suction cups (not shown), through the carrier members **530**, via connectors **545** into hoses **552**, through side connectors **560** on side **526a** of pipe. The positioning of hoses **552** can reduce the wear that the hoses might encounter when during movement of the effector, they interact or rub against other parts of the robot arm. From pipe **526** air is drawn through pipes **538** to the external vacuum source.

The hub assembly **522** is mounted with transversely oriented side plates **336** to pipe **526**, proximate the middle of the pipe **526**. Like the other components from which end effector **520** is assembled, side plates **536** are preferably made of light but durable materials such as aluminum.

Extending between and secured at ends to, plates **536** on both sides of pipe **526**, are cam block support rods **590**. Each rod **590** supports one of cam blocks **544a**, **544b** for sliding longitudinal movement thereon. Thus, cam blocks **544a**, **544b** form two parts of one actuation device. Cam block **544a** has secured to it, one end of cam rod **542a**, which is attached

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at its other end, to carrier **530a**. Cam block **544b** has secured to it, one end of cam rod (not shown but which is the same as rod **542a**) which is attached at its other end, to carrier **530k**.

Rotary cam disc **572**, forming a second actuation device, which is generally mounted and driven as described above and being interconnected to a rotating power source with shaft **578**. As described above, rotary cam **572** can be mounted to a moving connector member **524** of a Delta robot. Disc **572** has a pair of cam followers (engagement members) **574** positioned 180 degrees apart on the periphery of the disc **572**, each engaging one of the cam blocks **544**. Similar to the embodiment above, cam block **544a** has a transverse slot **546a** with opposing side surfaces **549a**, **549b**. Cam block **544b** is constructed in a similar manner.

To control and facilitate the movement of the pick-up members **530**, all the pick-up members **530a-k** are interconnected in a chain like manner as described above with tie links. All members **530a-k** are free to move along the guide rail **558**, but it should particularly noted that centrally located carriers **530e** and **530f** will have their movement in an outward direction constrained by the tie link between them, and their inward movement by the tie link or the actual carrier themselves.

Control of the movement of the pick-up members **530** is achieved by directly controlling the movement of pick-up members **530a** and **530k** using the actuation mechanism comprising the rotary disc **572**, cam followers **574**, cam blocks **544** and rods **542**.

In FIG. **11**, carriers **530** are shown in the diverged configuration with cam followers **574** in the approximately 3 o'clock and 9 o'clock position. By rotating cam disc **572** about 180 degrees or perhaps slightly less, in a counter clockwise direction from the position shown in FIG. **11**, cam blocks **544** will be moved toward and past the center of pipe **526**, thus pulling carrier members **530a** and **530k** to converge with other carrier members in the chain toward fixed carrier members **530e**, **530f**, and toward a central position, in a manner like that described above. When fully converged, all carrier members **530a-k** can be in abutment with each other. Alternatively, the inward movement can be constrained by the configuration of the tie links. By reversing the direction of movement of cam disc **572** to rotate about 180 degrees in a clockwise direction the carrier members can be returned to the diverged position shown in FIG. **11**.

These and other modifications and variations will readily become apparent to those of ordinary skill in the art without departing from the scope of the invention. For example, although in the embodiments shown herein, tie links between carriers are shown each of the same configuration, it is possible to vary the configuration of some of the tie links so that there are different configurations used. This could provide for non-constant spacing between the carrier members in the converged and/or diverged positions.

I claim:

1. An end effector for use with a moving device, said end effector comprising:

- a) a frame;
- b) a plurality of operational members configured for longitudinal movement on said frame;
- c) an actuation mechanism connected to a first operational member of said plurality of operational members and configured and operable to move said first operational member from a first position to a second position;
- d) a linking apparatus for linking said first operational member to a second operational member of said plural-

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ity of operational members said second operational member not directly connected to said actuation mechanism;

said actuation mechanism being configured and operable to move said first operational member from said first position to said second position, such that said second operational member is operable to be moved by said linking apparatus from a third position to a fourth position;

and wherein said actuation mechanism comprises:

- i) at least one cam block having a cam slot in an upper surface of said at least one cam block said cam slot extending in a generally transverse direction that is generally orthogonal to the direction of longitudinal movement, said at least one cam block also being configured for longitudinal movement relative to said frame;
- ii) a generally longitudinally oriented member attached to and extending between said at least one cam block and said first operational member;
- iii) a rotary cam configured and operable for rotation about an axis that is generally orthogonal to said direction of longitudinal movement and said transverse direction, said rotary cam being configured for connection to a rotatable drive shaft that is also rotatable generally about said axis; said rotary cam having at least one cam follower protruding from said rotary cam, wherein said at least one cam follower is configured and operable for movement transversely inside said cam slot of said at least one cam block and thus is operable to move said at least one cam block in a longitudinal direction during rotation of said rotary cam.

2. An end effector as claimed in claim 1 wherein said actuation mechanism is directly connected to a third operational member of said plurality of operational members and is configured and operable to move said third operational member from a fifth position to a sixth position, and from said sixth position to said fifth position, said linking apparatus also for linking said third operational member to a fourth operational member of said plurality of operational members;

and wherein when said actuation mechanism is configured and operable to move said third operational member from said fifth position to said sixth position, such that said fourth operational member is operable to be moved by said linking apparatus from a seventh position to an eighth position;

and wherein said at least one cam block comprises:

- a) a first cam block having a first cam slot in an upper surface of said first cam block extending generally in said transverse direction across said upper surface of said first cam block, said first cam block being configured for longitudinal movement relative to said frame;
- b) a second cam block having a second cam slot in an upper surface of said second cam block, said second cam slot extending generally in said transverse direction across said upper surface of said second cam block, said second cam block being positioned in parallel longitudinal relation to said first cam block and being configured for longitudinal movement relative to said frame;

and wherein said actuation mechanism further comprises:

- i) a first rod attached to said first cam block and to said first operational member;
- ii) a second rod attached to said second cam block and said third operational member;
- iii) and wherein said at least one cam follower protruding from said rotary cam comprises: (A) a first cam

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follower and wherein said first cam follower is configured and operable to move transversely inside said first cam slot of said first cam block and thus is operable to push said first cam block in a first direction during rotation of said rotary cam in a first rotational direction, and (B) a second cam follower, wherein said second cam follower is configured and operable to move transversely inside said second cam slot of said second cam block and thus is operable to push said second cam block in a direction opposite to said first direction during rotation of said rotary cam in said first rotational direction about said axis.

3. An end effector as claimed in claim 2 wherein said actuation mechanism is configured and operable to move said first operational member from said second position to said first position, such that said second operational member is operable to be moved by said linking apparatus from said fourth position to said third position.

4. An end effector as claimed in claim 2 wherein said linking apparatus is configured such that when said first operational member is at said first position and said second operational member is at said third position, the spacing between said first and second operational members is less than said spacing when said first operational member is at said second position and said second operational member is at said fourth position.

5. An end effector as claimed in claim 4 further comprising a fifth operational member, said fifth operational member being not directly connected to said actuation mechanism, said fifth operational member being linked by said linking apparatus to said second operational member, said actuation mechanism being configured and operable to move said first operational member from said first position to said second position, such that said second operational member is operable to be moved by said linking apparatus from a third position to a fourth position, and said fifth operational member is operable to be moved by said linking apparatus from a ninth position to a tenth position, and wherein said actuation mechanism is configured and operable to move said first operational member from said second position to said first position, said second operational member is operable to be moved from said fourth position to said third position, and said fifth operational member may be moved from said tenth position to said ninth position.

6. An end effector as claimed in claim 2 wherein said first, second, third, and fourth operational members are pick up members is operable to pick up and release at least one item.

7. An end effector as claimed in claim 6 further comprising a vacuum source that is interconnected and is operable to provide vacuum to said first, second, third and fourth pick-up members, wherein said vacuum source creates a suction force at a suction location on each of said first, second, third and fourth pick-up members, to lift and hold said at least one item.

8. An end effector as claimed in claim 1 wherein said rotatable shaft associated with said end effector is operable for driving said rotary cam about said axis, and a motor configured and operable to drive said rotatable shaft.

9. An end effector as claimed in claim 8 further comprising a controller associated with said moving device operable for controlling the motor and thus the rotation of said rotatable drive shaft.

10. An apparatus for moving a plurality of items comprising:

- a) a frame;
- b) a plurality of operational members mounted to said frame for movement generally in a longitudinal direction on said frame;

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c) an actuation mechanism mounted to said frame and connected to a first operational member of said plurality of operational members and configured and operable to move said first operational member longitudinally from a first position to a second position, and from said second position to said first position;

d) a linking apparatus for linking longitudinally said first operational member to a second operational member of said plurality of operational members, said second operational member being not directly connected to said actuation mechanism;

wherein said actuation mechanism comprises

- i) at least one cam block having a cam slot in an upper surface of said at least one cam block said cam slot extending in a generally transverse direction that is generally orthogonal to the direction of longitudinal movement and across said upper surface of said at least one cam block, said at least one cam block also being configured for longitudinal movement relative to said frame;

- ii) a connector connecting said at least one cam block and said first operational member;

- iii) a rotary cam configured and operable for rotation about an axis that is generally orthogonal to said direction of longitudinal movement and said transverse direction, said rotary cam having at least one cam follower protruding from said rotary cam, wherein said at least one cam follower is configured and operable to move transversely inside said cam slot of said at least one cam block and thus is operable to move said at least one cam block in said longitudinal direction during rotation of said rotary cam;

said rotary cam being configured for connection to a rotatable drive shaft that is also rotatable generally about said axis;

said rotary cam being configured and operable to rotate and thereby cause movement of said actuation mechanism and said actuation mechanism being configured and operable to move said first operational member longitudinally from said first position to said second position, such that said second operational member may be moved in said direction of longitudinal movement by said linking apparatus from a third position to a fourth position.

11. The apparatus of claim 10 wherein said apparatus comprises a robot having a robot arm, wherein said robot arm comprises a drive mechanism proximate to a distal end of said robot arm, said drive mechanism comprising said rotatable drive shaft operable for driving said rotary cam.

12. A robot as claimed in claim 10 wherein the rotatable shaft is operable for driving said rotary cam about said axis, and further comprising a motor operable for driving said rotatable shaft.

13. robot as claimed in claim 12 further comprising a controller for controlling the motor and thus the rotation of said rotatable shaft.

14. A robot as claimed in claim 12 further comprising a robot arm, said robot arm having a distal end of said robot arm from which protrudes said rotatable shaft.

15. A moving apparatus comprising:

- a. a frame;
- b. an operational member configured for movement generally in a longitudinal direction relative to said frame;
- c. an actuator configured and operable to move said operational member from a first position to a second position, and wherein said actuator comprises:

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- i) at least one cam block having a cam slot extending in a generally transverse direction that is generally orthogonal to said longitudinal direction, said at least one cam block also being mounted for movement in said longitudinal direction relative to said frame;
 - ii) a connector connecting said at least one cam block to said operational member;
 - iii) a rotary cam configured and operable for rotation about an axis that is generally orthogonal to said longitudinal direction and said transverse direction; said rotary cam being configured for connection to a rotatable drive shaft that is also operable for rotation generally about said axis;
- said rotary cam having at least one cam member, wherein said at least one cam member is configured and operable to move generally transversely inside said cam slot of said at least one cam block and thus said rotary cam is operable to move said at least one cam block generally in said longitudinal direction during rotation of said rotary cam, and thereby, due to said connector connecting said at least one cam block to said operational member, said rotary cam is operable to move said operational member generally in said longitudinal direction relative to said frame.

16. A moving apparatus as claimed in claim 15 wherein said operational member comprises a first operational member and wherein said apparatus further comprises (a) a second operational member configured for generally longitudinal movement relative to said frame and (b) a linking mechanism interconnecting said first and second operational members, said moving apparatus being configured and operable such that said cam member is operable to move said first operational member generally in said longitudinal direction and thereby, due to said linking mechanism, said cam member is operable to move said second operational member generally in said longitudinal direction.

17. A moving device as claimed in claim 15 wherein said at least one cam block comprises:

- a first cam block having a first cam slot in an upper surface of said first cam block extending generally in said transverse direction across said upper surface of said first cam block, said first cam block being configured for longitudinal movement relative to said frame;

- a second cam block having a second cam slot in an upper surface of said second cam block extending generally in said transverse direction across said upper surface of said second cam block, said second cam block being positioned in parallel longitudinal relation to said first cam block and being configured for longitudinal movement relative to said frame;

and wherein said actuation mechanism further comprises:

- a first connection mechanism interconnecting said first cam block and said first operational member;

- a second connection mechanism interconnecting said second cam block and a second operational member;

and wherein said at least one cam member comprises: (A)

- a first cam member configured and operable to move generally transversely inside said first cam slot of said first cam block and thereby be operable to push said first cam block generally in a first direction during rotation of said rotary cam in a first rotational direction, and (B) a second cam member configured and operable to move generally transversely inside said second cam slot of said second cam block and thereby be operable to push said second cam block in a direction opposite to said first

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direction during rotation of said rotary cam in said first rotational direction about said axis.

18. A robot as claimed in claim 15 the rotatable shaft is configured and operable for driving said rotary cam about said axis, and a motor associated configured and operable to drive said rotatable shaft.

19. A robot as claimed in claim 18 further comprising a controller is operable for controlling the motor and thus the rotation of said rotatable drive shaft.

20. A robot as claimed in claim 15 comprising first and second operational members configured for movement on said frame generally in said longitudinal direction relative to said frame, and an operational member interconnection mechanism interconnecting said first and second operational members, said actuator being configured and operable to move said first operational member from said first position to said second position, such that in co-operation with said first operational member and said operational member interconnection mechanism, said second operational member is operable to be moved by said operational member interconnection mechanism from a third position to a fourth position.

21. An end effector as claimed in claim 20 wherein said operational member interconnection mechanism is configured such that when said first operational member is at said first position and said second operational member is at said third position, the spacing between said first and second operational members is less than said spacing when said first operational member is at said second position and said second operational member is at said fourth position.

22. A method for lifting and transferring an item from a first location to a receptacle, said method comprising:

- a) moving a robot to position an end effector of a robot above said item;
- b) moving a first operational member of said end effector that is movable generally longitudinally using an actuator to a position directly above said item;
- c) lowering said end effector so that first operational member can pick up said item;
- d) raising said end effector;
- e) moving said robot to reposition said end effector above a receptacle;
- f) moving said first operational member with said actuator;
- g) moving said end effector toward said receptacle so that said item may be loaded inside said receptacle;
- h) releasing said item from said first operational member to load said receptacle with said item;

and wherein said end effector comprises:

- I) a frame;
- II) a first operational member configured for movement relative to said frame generally in a first direction;
- III) an actuator operable to move said first operational member generally in said first direction from a first position to a second position;

wherein said actuator comprises:

- i) a cam device having a cam surface oriented generally in a transverse direction that is orthogonal to said first direction, said cam device being configured for movement relative to said frame generally in said first direction;
- ii) a connector connecting said cam device to said operational member;
- iii) a rotary device configured to rotate about an axis of the rotary device and said rotary device being configured for connection to a rotatable drive shaft; said rotatable drive shaft being operable to rotate about a shaft axis;

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said shaft axis being configured generally orthogonal to said transverse direction and said first direction; said rotary device having at least one moving element; said rotary device being operable to be driven to rotate about said axis of said rotary device by rotation of said rotatable drive shaft such that:

said at least one moving element is moved generally against and along said cam surface of said cam device to move said cam device generally in said first direction; and

due to said connector connecting said operational member to said cam device, said at least one moving element is also operable to move said operational member generally in said first direction from said first position to said second position.

23. A moving apparatus comprising:

a frame;

an operational member configured for movement generally in a first direction relative to said frame;

an actuator operable to move said operational member from a first position to a second position relative to said frame, and wherein said actuator comprises:

a) a first actuation device being configured and operable for movement generally in said first direction relative to said frame;

b) a second actuation device being configured and operable for rotation about an axis that is generally orthogonal to said first direction; said second actuation device being configured for connection to a rotatable drive shaft that is also operable for rotation generally about said axis;

a connector connecting said actuator to said operational member;

said second actuation device being configured and operable to rotate about said axis to move said first actuation mechanism said first direction, resulting in movement of said operational member; and wherein:

one of said first actuation device and said second actuation device comprises a cam surface oriented generally in a transverse direction;

the other of said first actuation device and said second actuation device comprises an engagement element operable to engage said cam surface during rotation of said second actuation device about said axis;

wherein said axis is generally orthogonal to both said first direction and said transverse direction, and said transverse direction is also generally orthogonal to the first direction;

said second actuation device being operable to be driven to rotate about said axis such that:

said engagement element is operable to move generally along said cam surface to move said first actuation device generally in said first direction; and

due to said connector connecting said operational member to said actuator, said engagement element is also operable to move said operational member generally in said first direction from said first position to said second position.

24. An apparatus as claimed in claim **23** wherein apparatus comprises a robot and an end effector mounted to said robot and wherein said first actuation device is configured as part of said end effector and wherein said robot comprises at least part of said second actuation device.

25. An apparatus as claimed in claim **24** wherein said robot has a robot arm and wherein the rotatable drive shaft extends from said robot arm, said rotatable drive shaft being config-

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ured and operable for rotation such that said first actuation device is operable to be moved in said first direction.

26. An apparatus as claimed in claim **23** wherein said connector connects said first actuation device directly to said operational member.

27. An apparatus as claimed in claim **26** wherein said first actuation device comprises at least one cam block having at least one transversely oriented slot to provide said surface, and wherein said second actuation device further comprises a rotary device interconnected to said rotatable shaft to engage said surface of said transversely oriented slot.

28. A moving apparatus as claimed in claim **23** wherein the rotatable drive shaft is configured and operable for driving said rotary cam about said axis, and further comprising a motor configured and operable to drive said rotatable shaft.

29. A moving apparatus as claimed in claim **28** further comprising a controller operable for controlling the motor and thus the rotation of said rotatable shaft.

30. A moving apparatus as claimed in claim **29** comprising first and second operational members configured for movement on said frame generally in said longitudinal direction and an operational member interconnection mechanism interconnecting said first and second operational members, said actuator being configured and operable to move said first operational member from said first position to said second position, such that in co-operation with said first operational member and said operational member interconnection mechanism, said second operational member is operable to be moved by said interconnection mechanism from a third position to a fourth position.

31. A moving apparatus as claimed in claim **30** wherein said operational member interconnection mechanism is configured such that when said first operational member is at said first position and said second operational member is at said third position, the spacing between said first and second operational members is less than said spacing when said first operational member is at said second position and said second operational member is at said fourth position.

32. A moving apparatus comprising:

i) a frame;

ii) an operational member configured for movement relative to said frame generally in a first direction;

iii) an actuator operable to move said operational member generally in said first direction from a first position to a second position;

said actuator comprising:

a) a cam device having a cam surface oriented generally in a transverse direction that is orthogonal to said first direction, said cam device being configured for movement relative to said frame generally in said first direction;

b) a connector connecting said cam device to said operational member;

c) a rotary device configured to rotate about an axis of the rotary device and said rotary device being configured for connection to a rotatable drive shaft; said rotatable drive shaft being operable to rotate about a shaft axis;

said shaft axis being configured generally orthogonal to said transverse direction and said first direction; said rotary device having at least one moving element; said rotary device being operable to be driven to rotate about said axis of said rotary device by rotation of said rotatable drive shaft such that:

said at least one moving element is operable to move generally against and along said cam surface of

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said cam device to move said cam device generally in said first direction; and
 due to said connector connecting said operational member to said cam device, said at least one moving element is also operable to move said operational member generally in said first direction from said first position to said second position.

33. A moving apparatus as claimed in claim 32 comprising first and second operational members configured for movement on said frame generally in said first direction and further comprising an operational member interconnection mechanism interconnecting said first and second operational members, said actuation mechanism being configured and operable to move said first operational member from said first position to said second position, such that in co-operation with said first operational member and said operational member interconnection mechanism, said second operational member is operable to be moved by said operational member interconnection mechanism from a third position to a fourth position.

34. A moving apparatus as claimed in claim 33 wherein said operational member interconnection mechanism is configured such that when said first operational member is at said first position and said second operational member is at said third position, the spacing between said first and second operational members is less than said spacing when said first operational member is at said second position and said second operational member is at said fourth position.

35. A moving apparatus as claimed in claim 32 wherein said axis of the rotary device and the shaft axis are the same axis.

36. A moving apparatus as claimed in claim 35 wherein said moving apparatus further comprises said rotatable drive shaft that is operable to rotate about said shaft axis wherein said moving apparatus is configured such that said rotary device is operable to be driven in rotation about said axis of said rotary device.

37. A moving apparatus as claimed in claim 36 further comprising a motor operable to drive said rotatable drive shaft.

38. A moving apparatus as claimed in claim 32 wherein said moving element is a sliding element.

39. A moving apparatus as claimed in claim 38 further comprising a controller for controlling the motor and thus the rotation of said rotatable drive shaft.

40. A method for manufacturing a packaged product comprising loading an item into a receptacle using a moving apparatus, said moving apparatus comprising:

- I) an end effector having a frame and at least one operational member configured for movement generally in a first direction relative to said frame;
- II) an actuator operable to move said operational member generally in said first direction; and wherein said actuator comprises:
 - i) a cam device having a cam surface oriented generally in a transverse direction that is orthogonal to said first

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direction, said cam device being configured for movement relative to said frame generally in said first direction;

ii) a connector connecting said cam device to said operational member;

iii) a rotary device configured to rotate about an axis of the rotary device and said rotary device being configured for connection to a rotatable drive shaft; said rotatable drive shaft being operable to rotate about a shaft axis; said shaft axis being configured generally orthogonal to said transverse direction and said first direction; said rotary device having at least one moving element; said rotary device being operable to be driven to rotate about said axis of said rotary device by rotation of said rotatable drive shaft such that:

said at least one moving element is operable to move generally against and along said cam surface of said cam device to move said cam device generally in said first direction; and

due to said connector connecting said operational member to said cam device, said at least one moving element is also operable to move said operational member generally in said first direction from said first position to said second position,

said method comprising:

- a) positioning said operational member above an item;
- b) using said operational member to pick up said item;
- c) raising said item with said operational member;
- d) positioning said operational member above a receptacle;
- e) releasing said item from said operational member to load said receptacle with said item;
- f) during at least one of (a) to (e) above, rotating said rotary device about said axis thereby moving said at least one moving element against said cam surface of said cam device and thus moving said cam device and said operational member in said first direction.

41. A method as claimed in claim 40 wherein said axis of the rotary device and the shaft axis are the same axis.

42. A method as claimed in claim 41 wherein said moving apparatus further comprises said rotatable drive shaft that is operable to rotate about said shaft axis wherein said moving apparatus is configured such said rotary device is operable to be driven in rotation about said axis of said rotary device.

43. A method as claimed in claim 42 wherein said moving element is a sliding element.

44. A method as claimed in claim 42 wherein said moving apparatus further comprises a motor operable to drive said rotatable drive shaft.

45. A method as claimed in claim 44 wherein said moving apparatus further comprises a controller for controlling the motor and thus the rotation of said rotatable drive shaft.

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