

Title (en)
DEMOLITION HAMMER FOR A WORKING MACHINE EQUIPPED WITH A MANOEUVRABLE ARM

Title (de)
ABRISSHAMMER FÜR EINE ARBEITSMASCHINE MIT EINEM MANÖVRIERBAREN ARM

Title (fr)
MARTEAU DÉMOLISSEUR POUR ENGIN ÉQUIPÉ D'UN BRAS MAN UVRABLE

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Application
EP 11838324 A 20111102

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Abstract (en)
[origin: WO2012060773A1] The invention concerns a demolition arrangement for a remote-controlled working machine (1) equipped with a manoeuvrable arm (9), which machine, electrically powered and able to be driven on tracks (17), is principally intended for destruction and demolition work through the demolition processing with an impact tool (50) that operates through a hydraulically powered hammer (32) and where an operator walking next to the machine controls its various movements with a remote-control unit (4), which machine has a chassis (5) with an upper part (6) that is mounted in bearings on a lower part (7) in a manner that allows rotation for the rotation of the upper part in a horizontal plane around a vertical axis (8), whereby the manoeuvrable arm is supported at the upper part and including a series of arm parts (10, 11, 12) mutually joined to each other and that can be manoeuvred in a vertical plane by associated hydraulic cylinders (13, 14, 15), a link system (20) arranged at the free end of the arm that can be adjusted by means of a hydraulic cylinder (29) and designed as a combination of a coupling arrangement (21) for the attachment of a tool and a tilt or demolition arrangement (22) for the controlled oscillation around the centre of an axis (23) at the free end of the manoeuvrable arm of an impact tool inserted into the hammer. In order to make the work of demolition efficient, a rotary joint (35) is arranged at one of the arm sections (12) that are a component of the manoeuvrable arm (9), which rotary joint allows, through the influence of a rotator (36) a forward arm subsection (12:2) of the arm section, on which arm subsection the link system (20) is located, to place the end of the impact tool (50) that is located farthest forward against a working point in space though the forward arm subsection (12:2) being rotated around the longitudinal axis (A) of the arm section (12).

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Citation (search report)
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• [Y] JP H0839235 A 19960213 - MARUMA TRACTOR & EQUIP
• [Y] US 5388842 A 19950214 - PIRAS BERNARD [FR], et al
• See references of WO 2012060773A1

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