Title (en)
  ROBOTIC VISION

Title (de)
  ROBOTERSICHT

Title (fr)
  VISION ROBOTIQUE

Publication
  EP 3972787 A4 20220727 (EN)

Application
  EP 20861193 A 20200601

Priority
  • US 202016792009 A 20200214
  • US 201962895310 P 20190903
  • KR 2020007081 W 20200601

Abstract (en)
  [origin: WO2021045350A1] A method includes accessing RGB and depth image data representing a scene that includes at least a portion of a robotic limb. Using this data, a computing system may segment the image data to isolate and identify at least a portion of the robotic limb within the scene. The computing system can determine a current pose of the robotic limb within the scene based on the image data, joint data, or a 3D virtual model of the robotic limb. The computing system may then determine a desired goal pose, which may be based on the image data or the 3D virtual model. Based on the determined goal pose, the computing device determines the difference between the current pose and the goal pose of the robotic limb, and using this difference, provides a pose adjustment that for the robotic limb.

IPC 8 full level
  B25J 9/16 (2006.01)

CPC (source: EP)
  B25J 9/1692 (2013.01); **B25J 9/1697** (2013.01); B25J 9/161 (2013.01); G05B 2219/39017 (2013.01); G05B 2219/39057 (2013.01); G05B 2219/39393 (2013.01); G05B 2219/39397 (2013.01)

Citation (search report)
  • [A] WO 2018236753 A1 20181227 - GOOGLE LLC [US]
  • [XI] BOHG JEANNETTE ET AL: "Robot arm pose estimation through pixel-wise part classification", 2014 IEEE INTERNATIONAL CONFERENCE ON ROBOTICS AND AUTOMATION (ICRA), IEEE, 31 May 2014 (2014-05-31), pages 3143 - 3150, XP032650930, DOI: 10.1109/ICRA.2014.6907311
  • See references of WO 2021045350A1

Designated contracting state (EPC)
  AL AT BE BG CH CY CZ DE DK EE ES FI FR GB GR HR HU IE IS IT LI LT LU LV MC MK MT NL NO PL PT RO RS SE SI SK SM TR

Designated extension state (EPC)
  BA ME

DOCDB simple family (publication)
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DOCDB simple family (application)
  KR 2020007081 W 20200601; EP 20861193 A 20200601