Title (en)

MOVEMENT CONTROL METHOD FOR OMNIDIRECTIONAL AUTOMATIC FORKLIFT, AND OMNIDIRECTIONAL AUTOMATIC FORKLIFT

Title (de)

VERFAHREN ZUR BEWEGUNGSSTEUERUNG EINES AUTOMATISCHEN OMNIDIREKTIONALEN GABELSTAPLERS UND AUTOMATISCHER OMNIDIREKTIONALER GABELSTAPLER

Title (fr)

PROCÉDÉ DE COMMANDE DE MOUVEMENTS DE CHARIOT ÉLÉVATEUR AUTOMATIQUE OMNIDIRECTIONNEL ET CHARIOT AUTOMATIQUE OMNIDIRECTIONNEL

Publication

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Application

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Priority

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Abstract (en)

The prevent invention relates to a movement control method for an omnidirectional automatic forklift (100), wherein the omnidirectional automatic forklift (100) comprises a vehicle body (110) and fork arms (120), the movement control method comprising: S101: controlling the omnidirectional automatic forklift (100) to travel at a first preset speed; S102: judging, when an obstacle is detected, the obstacle and determining an effective obstacle; S103: calculating a distance between the effective obstacle and the omnidirectional automatic forklift (100), and determining an obstacle-avoiding deceleration according to the distance; S104: controlling the omnidirectional automatic forklift (100) to travel at the obstacle-avoiding deceleration; and S105: judging whether the obstacle disappears, and returning to step S101 if the obstacle disappears. With the examples of the present invention, the omnidirectional safe obstacle avoidance is realized in an omnidirectional automatic forklift (100).

IPC 8 full level

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CPC (source: CN EP)

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Citation (search report)
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- [XI] US 2021087031 A1 20210325 - LUNSCHER NOLAN [CA], et al

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