

CPC COOPERATIVE PATENT CLASSIFICATION

B25J **MANIPULATORS; CHAMBERS PROVIDED WITH MANIPULATION DEVICES**
({manipulators specially adapted for use in surgery [A61B 34/70](#); manipulators used in cleaning hollow articles [B08B 9/04](#) } ; manipulators associated with rolling mills [B21B 39/20](#); manipulators associated with forging machines [B21J 13/10](#); { manipulators associated with picking-up and placing mechanisms [B23P 19/007](#) } ; means for holding wheels or parts thereof [B60B 30/00](#); { vehicles with ground-engaging propulsion means, e.g. walking members [B62D 57/02](#), [B62D 57/032](#); devices for picking-up and depositing articles or materials between conveyors [B65G 47/90](#), [B65G 47/91](#); manipulators with gripping or holding means for transferring packages [B65H 67/065](#) } ; cranes [B66C](#); { manipulators used in the protection or supervision of pipe-line installations [F17D 5/00](#); walking equipment adapted for nuclear steam-generators [F22B 37/006](#) } ; manipulators specially adapted for, or associated with, nuclear reactors [G21C](#); { apparatus used for handling wafers during manufacture or treatment of semiconductor [H01L 21/68](#) })

NOTE

In this subclass, the following term is used with the meaning indicated :

- "manipulator" covers handling tools, devices, or machines having a gripping or work head capable of bodily movement in space and of change of orientation, such bodily movement and change of orientation being controlled, at will, by means remote from the head.

WARNING

The following IPC groups are not used in the CPC scheme. Subject matter covered by these groups is classified in the following CPC groups:

B25J 9/18	covered by	B25J 9/16
B25J 9/22	covered by	B25J 9/1656 , G05B 19/42

1/00	Manipulators positioned in space by hand (of master-slave type B25J 3/00; micromanipulators B25J 7/00)	5/04	. . wherein the guideway is also moved, e.g. travelling crane bridge type
1/02	. articulated or flexible	5/06	. Manipulators combined with a control cab for the operator
1/04	. rigid, e.g. shelf-reachers { (without grippers A47F 13/06) }	7/00	Micromanipulators { (specimen supports for investigating or analysing materials G01N 23/2204 ; associated with microscopes G02B 21/32 ; means for supporting or positioning the objects or the material in discharge tubes H01J 37/20) }
1/06	. of the lazy-tongs type	9/00	Programme-controlled manipulators
1/08	. movably mounted in a wall	9/0003	. { Home robots, i.e. small robots for domestic use }
1/10	. . Sleeve and pivot mountings therefor	9/0006	. { Exoskeletons, i.e. resembling a human figure }
1/12	. having means for attachment to a support stand	9/0009	. { Constructional details, e.g. manipulator supports, bases }
3/00	Manipulators of master-slave type, i.e. both controlling unit and controlled unit perform corresponding spatial movements	9/0012	. . { making use of synthetic construction materials, e.g. plastics, composites }
3/02	. involving a parallelogram coupling of the master and slave units (pantographic instruments B43L 13/00)	9/0015	. . { Flexure members, i.e. parts of manipulators having a narrowed section allowing articulation by flexion }
3/04	. involving servo mechanisms (servo-actuated heads B25J 15/02)	9/0018	. . { Bases fixed on ceiling, i.e. upside down manipulators }
5/00	Manipulators mounted on wheels or on carriages (B25J 1/00 takes precedence; programme-controlled manipulators B25J 9/00; { vehicle aspects B60, B62, e.g. remote-controlled steering for motor vehicles B62D 1/24; control of position of vehicles G05D 1/00 })	9/0021	. . { All motors in base }
5/002	. { mounted on an air cushion }	9/0024	. . { Wrist motors at rear part of the upper arm }
5/005	. { mounted on endless tracks or belts }	9/0027	. . { Means for extending the operation range }
5/007	. { mounted on wheels }	9/003	. { having parallel kinematics }
5/02	. travelling along a guideway	9/0033	. . { with kinematics chains having a prismatic joint at the base }
		9/0036	. . . { with kinematics chains of the type prismatic-rotary-rotary }

- 9/0039 . . . {with kinematics chains of the type prismatic-spherical-spherical}
- 9/0042 . . . {with kinematics chains of the type prismatic-universal-universal}
- 9/0045 . . {with kinematics chains having a rotary joint at the base}
- 9/0048 . . . {with kinematics chains of the type rotary-rotary-rotary}
- 9/0051 . . . {with kinematics chains of the type rotary-universal-universal or rotary-spherical-spherical, e.g. Delta type manipulators}
- 9/0054 . . {with kinematics chains having a spherical joint at the base}
- 9/0057 . . . {with kinematics chains of the type spherical-prismatic-spherical}
- 9/006 . . . {with kinematics chains of the type spherical-prismatic-universal}
- 9/0063 . . {with kinematics chains having an universal joint at the base}
- 9/0066 . . . {with kinematics chains of the type universal-prismatic-spherical}
- 9/0069 . . . {with kinematics chains of the type universal-prismatic-universal}
- 9/0072 . . {of the hybrid type, i.e. having different kinematics chains}
- 9/0075 . . {Truss}
- 9/0078 . . {actuated by cables}
- 9/0081 . {with master teach-in means}
- 9/0084 . {comprising a plurality of manipulators}
- 9/0087 . . {Dual arms (double SCARA arms [B25J 9/043](#))}
- 9/009 . . {being mechanically linked with one another at their distal ends}
- 9/0093 . {co-operating with conveyor means}
- 9/0096 . {co-operating with a working support, e.g. work-table}
- 9/02 . characterised by movement of the arms, e.g. cartesian coordinate type ([B25J 9/06 takes precedence](#))
- 9/023 . . {Cartesian coordinate type}
- 9/026 . . . {Gantry-type}
- 9/04 . . by rotating at least one arm, excluding the head movement itself, e.g. cylindrical coordinate type or polar coordinate type
- 9/041 . . . {Cylindrical coordinate type}
- 9/042 {comprising an articulated arm}
- 9/043 {double SCARAR arms}
- 9/044 {with forearm providing vertical linear movement}
- 9/045 . . . {Polar coordinate type}
- 9/046 . . . {Revolute coordinate type}
- 9/047 {the pivoting axis of the first arm being offset to the vertical axis}
- 9/048 . . . {Pendulum type}
- 9/06 . characterised by multi-articulated arms
- 9/065 . . {Snake robots}
- 9/08 . characterised by modular constructions
- 9/10 . characterised by positioning means for manipulator elements
- 9/1005 . . {comprising adjusting means}
- 9/101 . . . {using limit-switches, -stops}
- 9/1015 . . . {using additional, e.g. micro adjustment of the end effector}
- 9/102 . . {Gears specially adapted therefor, e.g. reduction gears ([gearing in general F16H](#))}
- 9/1025 . . . {Harmonic drives ([in general: F16H 49/001](#))}
- 9/103 . . . {with backlash-preventing means}
- 9/1035 . . . {Pinion and fixed rack drivers, e.g. for rotating an upper arm support on the robot base}
- 9/104 . . {with cables, chains or ribbons}
- 9/1045 . . . {comprising tensioning means}
- 9/105 . . {using eccentric means ([B25J 9/109 takes precedence](#))}
- 9/1055 . . {by gravity}
- 9/106 . . {with articulated links}
- 9/1065 . . . {with parallelograms}
- 9/107 {of the froglegs type}
- 9/1075 . . {with muscles or tendons}
- 9/108 . . {Bearings specially adapted therefor ([bearings in general F16C](#))}
- 9/1085 . . {positioning by means of shape-memory materials ([shape memory actuators F03G 7/06](#))}
- 9/109 . . {comprising mechanical programming means, e.g. cams}
- 9/1095 . . {chemically actuated}
- 9/12 . . electric
- 9/123 . . . {Linear actuators}
- 9/126 . . . {Rotary actuators}
- 9/14 . . fluid
- 9/142 . . . {comprising inflatable bodies}
- 9/144 . . . {Linear actuators}
- 9/146 . . . {Rotary actuators}
- 9/148 {of the oscillating vane-type ([in general F15B 15/12](#))}
- 9/16 . Programme controls ([programme controls in general G05B 19/00, e.g. numerical programme controls G05B 19/18; recording or playback systems G05B 19/42](#))}
- 9/1602 . . {characterised by the control system, structure, architecture}
- 9/1605 . . . {Simulation of manipulator lay-out, design, modelling of manipulator}
- 9/1607 . . . {Calculation of inertia, jacobian matrixes and inverses}
- 9/161 . . . {Hardware, e.g. neural networks, fuzzy logic, interfaces, processor}
- 9/1612 . . {characterised by the hand, wrist, grip control}
- 9/1615 . . {characterised by special kind of manipulator, e.g. planar, scara, gantry, cantilever, space, closed chain, passive/active joints and tendon driven manipulators}
- 9/1617 . . . {Cellular, reconfigurable manipulator, e.g. cebot}
- 9/162 . . . {Mobile manipulator, movable base with manipulator arm mounted on it}
- 9/1623 . . . {Parallel manipulator, Stewart platform, links are attached to a common base and to a common platform, plate which is moved parallel to the base}
- 9/1625 . . . {Truss-manipulator for snake-like motion}
- 9/1628 . . {characterised by the control loop}
- 9/163 . . . {learning, adaptive, model based, rule based expert control}
- 9/1633 . . . {compliant, force, torque control, e.g. combined with position control}
- 9/1635 . . . {flexible-arm control}

9/1638	. . . {compensation for arm bending/inertia, pay load weight/inertia}	11/008	. {Manipulators for service tasks}
9/1641	. . . {compensation for backlash, friction, compliance, elasticity in the joints}	11/0085	. . {Cleaning}
9/1643	. . . {redundant control}	11/009	. . {Nursing, e.g. carrying sick persons, pushing wheelchairs, distributing drugs}
9/1646	. . . {variable structure system, sliding mode control}	11/0095	. {Manipulators transporting wafers}
9/1648	. . . {non-linear control combined or not with linear control}	13/00	Controls for manipulators (programme controls B25J 9/16; control in general G05)
9/1651	. . . {acceleration, rate control}	13/003	. {by means of an audio-responsive input (audible safety signals B25J 19/061)}
9/1653	. . . {parameters identification, estimation, stiffness, accuracy, error analysis}	13/006	. {by means of a wireless system for controlling one or several manipulators}
9/1656	. . {characterised by programming, planning systems for manipulators}	13/02	. Hand grip control means {(handles or pedals for crane control B66C 13/56 ; for measuring the force applied to control members G01L 5/22 ; hand-held casings for switching devices, e.g. joy-sticks H01H 9/0214)}
9/1658	. . . {characterised by programming language}	13/025	. . {comprising haptic means}
9/1661	. . . {characterised by task planning, object-oriented languages}	13/04	. Foot-operated control means
9/1664	. . . {characterised by motion, path, trajectory planning}	13/06	. Control stands, e.g. consoles, switch-boards
9/1666 {Avoiding collision or forbidden zones}	13/065	. . {comprising joy-sticks}
9/1669	. . . {characterised by special application, e.g. multi-arm co-operation, assembly, grasping}	13/08	. by means of sensing devices, e.g. viewing or touching devices
9/1671	. . . {characterised by simulation, either to verify existing program or to create and verify new program, CAD/CAM oriented, graphic oriented programming systems}	13/081	. . {Touching devices, e.g. pressure-sensitive}
9/1674	. . {characterised by safety, monitoring, diagnostic}	13/082	. . . {Grasping-force detectors (in general G01L 5/16 , G01L 5/22)}
9/1676	. . . {Avoiding collision or forbidden zones}	13/083 {fitted with slippage detectors}
9/1679	. . {characterised by the tasks executed}	13/084	. . . {Tactile sensors (in general G01L 5/16 , G01L 5/22)}
9/1682	. . . {Dual arm manipulator; Coordination of several manipulators}	13/085	. . {Force or torque sensors (B25J 13/082 , B25J 13/084 take precedence)}
9/1684	. . . {Tracking a line or surface by means of sensors}	13/086	. . {Proximity sensors}
9/1687	. . . {Assembly, peg and hole, palletising, straight line, weaving pattern movement}	13/087	. . {for sensing other physical parameters, e.g. electrical or chemical properties}
9/1689	. . . {Teleoperation}	13/088	. . {with position, velocity or acceleration sensors}
9/1692	. . . {Calibration of manipulator}	13/089	. . . {Determining the position of the robot with reference to its environment}
9/1694	. . {characterised by use of sensors other than normal servo-feedback from position, speed or acceleration sensors, perception control, multi-sensor controlled systems, sensor fusion}	15/00	Gripping heads {and other end effectors (grippers used in machine tools B23Q 7/04; gripping members fitted on cranes B66C 1/42, B66C 1/44; gripping means used in the manufacture of semiconductors H01L 21/68707; gripping means used for mounting electrical components H05K 13/04)}
9/1697	. . . {Vision controlled systems}	15/0004	. {with provision for adjusting the gripped object in the hand}
9/20	. . fluidic	15/0009	. {comprising multi-articulated fingers, e.g. resembling a human hand}
11/00	Manipulators not otherwise provided for	15/0014	. {having fork, comb or plate shaped means for engaging the lower surface on a object to be transported}
11/0005	. {Manipulators having means for high-level communication with users, e.g. speech generator, face recognition means}	15/0019	. {End effectors other than grippers}
11/001	. . {with emotions simulating means}	15/0023	. {Gripper surfaces directly activated by a fluid (flexible fingers B25J 15/12)}
11/0015	. . {Face robots, animated artificial faces for imitating human expressions}	15/0028	. {with movable, e.g. pivoting gripping jaw surfaces}
11/002	. {Manipulators for defensive or military tasks}	15/0033	. {with gripping surfaces having special shapes}
11/0025	. . {handling explosives, bombs or hazardous objects}	15/0038	. . {Cylindrical gripping surfaces}
11/003	. {Manipulators for entertainment}	15/0042	. . {V-shaped gripping surfaces}
11/0035	. . {Dancing, executing a choreography}	15/0047	. {for internally gripping hollow or recessed objects}
11/004	. . {Playing a music instrument}	15/0052	. {multiple gripper units or multiple end effectors}
11/0045	. {Manipulators used in the food industry}	15/0057	. . {mounted on a turret}
11/005	. {Manipulators for mechanical processing tasks}	15/0061	. . {mounted on a modular gripping structure}
11/0055	. . {Cutting}		
11/006	. . {Deburring or trimming}		
11/0065	. . {Polishing or grinding}		
11/007	. . {Riveting}		
11/0075	. {Manipulators for painting or coating}		

- 15/0066 . . {with different types of end effectors, e.g. gripper and welding gun ([B25J 15/0057](#) and [B25J 15/0061](#) take precedence)}
- 15/0071 . {with needles engaging into objects to be gripped}
- 15/0076 . {with means, e.g. Pelletier elements, for freezing a fluid interface between the gripping head and an object to be gripped}
- 15/008 . {with sticking, gluing or adhesive means}
- 15/0085 . {with means for applying an electrostatic force on the object to be gripped}
- 15/009 . {with pins for accurately positioning the object on the gripping head}
- 15/0095 . {with an external support, i.e. a support which does not belong to the manipulator or the object to be gripped, e.g. for maintaining the gripping head in an accurate position, guiding it or preventing vibrations}
- 15/02 . servo-actuated
- 15/0206 . . {comprising articulated grippers}
- 15/0213 . . . {actuated by gears}
- 15/022 . . . {actuated by articulated links}
- 15/0226 . . . {actuated by cams}
- 15/0233 . . . {actuated by chains, cables or ribbons}
- 15/024 . . . {having fingers directly connected to actuator}
- 15/0246 . . {actuated by an electromagnet}
- 15/0253 . . {comprising parallel grippers}
- 15/026 . . . {actuated by gears}
- 15/0266 . . . {actuated by articulated links}
- 15/0273 {comprising linear guide means}
- 15/028 . . . {actuated by cams}
- 15/0286 . . . {actuated by chains, cables or ribbons}
- 15/0293 . . . {having fingers directly connected to actuator}
- 15/04 . with provision for the remote detachment or exchange of the head or parts thereof
- 15/0408 . . {Connections means}
- 15/0416 . . . {having balls}
- 15/0425 . . . {having cams}
- 15/0433 . . . {having gripping members}
- 15/0441 . . . {having vacuum or magnetic means}
- 15/045 . . . {having screw means}
- 15/0458 . . . {having a frustoconical member}
- 15/0466 . . {with means for checking exchange completion}
- 15/0475 . . {Exchangeable fingers}
- 15/0483 . . {with head identification means}
- 15/0491 . . {comprising end-effector racks}
- 15/06 . with vacuum or magnetic holding means
- 15/0608 . . {with magnetic holding means}
- 15/0616 . . {with vacuum}
- 15/0625 . . . {provided with a valve}
- 15/0633 {Air-flow-actuated valves}
- 15/0641 {Object-actuated valves}
- 15/065 . . . {provided with separating means for releasing the gripped object after suction}
- 15/0658 {Pneumatic type, e.g. air blast or overpressure}
- 15/0666 {Other types, e.g. pins or springs}
- 15/0675 . . . {of the ejector type}
- 15/0683 . . . {Details of suction cup structure, e.g. grooves or ridges}
- 15/0691 . . . {Suction pad made out of porous material, e.g. sponge or foam}
- 15/08 . having finger members ([B25J 15/02](#), [B25J 15/04](#) take precedence)
- 15/083 . . {with means for locking the fingers in an open or closed position}
- 15/086 . . {with means for synchronizing the movements of the fingers}
- 15/10 . . with three or more finger members
([B25J 15/0009](#) takes precedence)}
- 15/103 . . . {for gripping the object in three contact points}
- 15/106 . . . {moving in parallel relationship}
- 15/12 . . with flexible finger members
- 17/00 Joints**
- 17/02 . Wrist joints
- 17/0208 . . {Compliance devices}
- 17/0216 . . . {comprising a Stewart mechanism}
- 17/0225 . . . {with axial compliance, i.e. parallel to the longitudinal wrist axis}
- 17/0233 . . . {with radial compliance, i.e. perpendicular to the longitudinal wrist axis}
- 17/0241 . . {One-dimensional joints}
- 17/025 . . . {mounted in series}
- 17/0258 . . {Two-dimensional joints}
- 17/0266 . . . {comprising more than two actuating or connecting rods}
- 17/0275 . . . {Universal joints, e.g. Hooke, Cardan, ball joints}
- 17/0283 . . {Three-dimensional joints}
- 17/0291 . . . {having axes crossing at an oblique angle, i.e. other than 90 degrees}
- 18/00 Arms**
- 18/002 . {comprising beam bending compensation means}
- 18/005 . {having a curved shape}
- 18/007 . {the end effector rotating around a fixed point}
- 18/02 . extensible
- 18/025 . . {telescopic}
- 18/04 . . rotatable
- 18/06 . flexible
- 19/00 Accessories fitted to manipulators, e.g. for monitoring, for viewing; Safety devices combined with or specially adapted for use in connection with manipulators (safety-devices in general [F16P](#); protection against radiation in general [G21F](#))**
- 19/0004 . {Braking devices (brakes in general [F16D](#))}
- 19/0008 . {Balancing devices}
- 19/0012 . . {using fluidic devices}
- 19/0016 . . {using springs}
- 19/002 . . {using counterweights}
- 19/0025 . {Means for supplying energy to the end effector}
- 19/0029 . . {arranged within the different robot elements}
- 19/0033 . . . {with axial connectors in end effector flange}
- 19/0037 . . . {comprising a light beam pathway, e.g. laser}
- 19/0041 . . . {having rotary connection means}
- 19/0045 . . {Contactless power transmission, e.g. by magnetic induction}
- 19/005 . {using batteries, e.g. as a back-up power source}
- 19/0054 . {Cooling means}
- 19/0058 . {Means for cleaning manipulators, e.g. dust removing means}
- 19/0062 . {Lubrication means}
- 19/0066 . {Means or methods for maintaining or repairing manipulators}
- 19/007 . {Means or methods for designing or fabricating manipulators}

- 19/0075 . {Means for protecting the manipulator from its environment or vice versa}
- 19/0079 . . {using an internal pressure system}
- 19/0083 . . {using gaiters}
- 19/0087 . . {using an antibacterial coating}
- 19/0091 . {Shock absorbers (in general [F16F](#))}
- 19/0095 . {Means or methods for testing manipulators}
- 19/02 . Sensing devices
- 19/021 . . {Optical sensing devices}
- 19/022 . . . {using lasers}
- 19/023 . . . {including video camera means}
- 19/025 . . . {including optical fibres}
- 19/026 . . {Acoustical sensing devices}
- 19/027 . . {Electromagnetic sensing devices}
- 19/028 . . {Piezoresistive or piezoelectric sensing devices}
- 19/04 . . Viewing devices
- 19/06 . Safety devices
- 19/061 . . {with audible signals ([audio controls B25J 13/003](#))}
- 19/063 . . {working only upon contact with an outside object}
- 19/065 . . . {Mechanical fuse}
- 19/066 . . {Redundant equipment}
- 19/068 . . {Actuating means with variable stiffness}
- 21/00** **Chambers provided with manipulation devices**
(constructional features of the mounting of the manipulator in the wall [B25J 1/08](#); {glove-boxes for nuclear applications [G21F 7/04](#)})
- 21/005 . {Clean rooms}
- 21/02 . Glove-boxes, i.e. chambers in which manipulations are performed by the human hands in gloves built into the chamber walls {(glove- boxes for removal of dirt [B08B 15/026](#); glove-boxes shielded against radiation [G21F 7/04](#))}; Gloves therefor