

# CPC COOPERATIVE PATENT CLASSIFICATION

## B PERFORMING OPERATIONS; TRANSPORTING (NOTES omitted)

### SHAPING

## B25 HAND TOOLS; PORTABLE POWER-DRIVEN TOOLS; MANIPULATORS (NOTE omitted)

**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.

#### WARNINGS

- The following IPC groups are not in the CPC scheme. The subject matter for these IPC groups is classified in the following CPC groups:  

<a href="#">B25J 9/18</a>	covered by	<a href="#">B25J 9/16</a>
<a href="#">B25J 9/22</a>	covered by	<a href="#">B25J 9/1656</a> , <a href="#">G05B 19/42</a>
- In this subclass non-limiting references (in the sense of paragraph 39 of the Guide to the IPC) may still be displayed in the scheme.

<b>1/00</b>	<b>Manipulators positioned in space by hand (of master-slave type <a href="#">B25J 3/00</a>; micromanipulators <a href="#">B25J 7/00</a>)</b>	<b>5/00</b>	<b>Manipulators mounted on wheels or on carriages (<a href="#">B25J 1/00</a> takes precedence; programme-controlled manipulators <a href="#">B25J 9/00</a> { ; vehicle aspects <a href="#">B60</a>, <a href="#">B62</a>, e.g. remote-controlled steering for motor vehicles <a href="#">B62D 1/24</a>; control of position of vehicles <a href="#">G05D 1/00</a> } )</b>
1/02	• articulated or flexible	5/002	• {mounted on an air cushion}
1/04	• rigid, e.g. shelf-reachers { (without grippers <a href="#">A47F 13/06</a> ) }	5/005	• {mounted on endless tracks or belts}
1/06	• of the lazy-tongs type	5/007	• {mounted on wheels}
1/08	• movably mounted in a wall	5/02	• travelling along a guideway
1/10	• . Sleeve and pivot mountings therefor	5/04	• . wherein the guideway is also moved, e.g. travelling crane bridge type
1/12	• having means for attachment to a support stand	5/06	• Manipulators combined with a control cab for the operator
<b>3/00</b>	<b>Manipulators of master-slave type, i.e. both controlling unit and controlled unit perform corresponding spatial movements</b>		
3/02	• involving a parallelogram coupling of the master and slave units (pantographic instruments <a href="#">B43L 13/00</a> )		
3/04	• involving servo mechanisms (servo-actuated heads <a href="#">B25J 15/02</a> )		

7/00	<b>Micromanipulators</b> {(specimen supports for investigating or analysing materials <a href="#">G01N 23/2204</a> ; associated with microscopes <a href="#">G02B 21/32</a> ; means for supporting or positioning the objects or the material in discharge tubes <a href="#">H01J 37/20</a> )}	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
9/00	<b>Programme-controlled manipulators</b>	9/041	. . . {Cylindrical coordinate type}
9/0003	. {Home robots, i.e. small robots for domestic use}	9/042	. . . . {comprising an articulated arm}
9/0006	. {Exoskeletons, i.e. resembling a human figure}	9/043	. . . . . {double selective compliance articulated robot arms [SCARA]}
9/0009	. {Constructional details, e.g. manipulator supports, bases}	9/044	. . . . . {with forearm providing vertical linear movement}
9/0012	. . {making use of synthetic construction materials, e.g. plastics, composites}	9/045	. . . {Polar coordinate type}
9/0015	. . {Flexure members, i.e. parts of manipulators having a narrowed section allowing articulation by flexion}	9/046	. . . {Revolute coordinate type}
9/0018	. . {Bases fixed on ceiling, i.e. upside down manipulators}	9/047	. . . . {the pivoting axis of the first arm being offset to the vertical axis}
9/0021	. . {All motors in base}	9/048	. . . {Pendulum type}
9/0024	. . {Wrist motors at rear part of the upper arm}	9/06	. characterised by multi-articulated arms
9/0027	. . {Means for extending the operation range}	9/065	. . {Snake robots}
9/003	. {having parallel kinematics}	9/08	. characterised by modular constructions
9/0033	. . {with kinematics chains having a prismatic joint at the base}	9/10	. characterised by positioning means for manipulator elements
9/0036	. . . {with kinematics chains of the type prismatic-rotary-rotary}	9/1005	. . {comprising adjusting means}
9/0039	. . . {with kinematics chains of the type prismatic-spherical-spherical}	9/101	. . . {using limit-switches, -stops}
9/0042	. . . {with kinematics chains of the type prismatic-universal-universal}	9/1015	. . . {using additional, e.g. microadjustment of the end effector}
9/0045	. . {with kinematics chains having a rotary joint at the base}	9/102	. . {Gears specially adapted therefor, e.g. reduction gears ( <a href="#">gearings in general F16H</a> )}
9/0048	. . . {with kinematics chains of the type rotary-rotary-rotary}	9/1025	. . . {Harmonic drives ( <a href="#">in general: F16H 49/001</a> )}
9/0051	. . . {with kinematics chains of the type rotary-universal-universal or rotary-spherical-spherical, e.g. Delta type manipulators}	9/103	. . . {with backlash-preventing means}
9/0054	. . {with kinematics chains having a spherical joint at the base}	9/1035	. . . {Pinion and fixed rack drivers, e.g. for rotating an upper arm support on the robot base}
9/0057	. . . {with kinematics chains of the type spherical-prismatic-spherical}	9/104	. . {with cables, chains or ribbons}
9/006	. . . {with kinematics chains of the type spherical-prismatic-universal}	9/1045	. . . {comprising tensioning means}
9/0063	. . {with kinematics chains having an universal joint at the base}	9/105	. . {using eccentric means ( <a href="#">B25J 9/109 takes precedence</a> )}
9/0066	. . . {with kinematics chains of the type universal-prismatic-spherical}	9/1055	. . {by gravity}
9/0069	. . . {with kinematics chains of the type universal-prismatic-universal}	9/106	. . {with articulated links}
9/0072	. . {of the hybrid type, i.e. having different kinematics chains}	9/1065	. . . {with parallelograms}
9/0075	. . {Truss}	9/107	. . . . {of the froglegs type}
9/0078	. . {actuated by cables}	9/1075	. . {with muscles or tendons}
9/0081	. {with master teach-in means}	9/108	. . {Bearings specially adapted therefor ( <a href="#">bearings in general F16C</a> )}
9/0084	. {comprising a plurality of manipulators}	9/1085	. . {positioning by means of shape-memory materials ( <a href="#">shape memory actuators F03G 7/06</a> )}
9/0087	. . {Dual arms ( <a href="#">double SCARA arms B25J 9/043</a> )}	9/109	. . {comprising mechanical programming means, e.g. cams}
9/009	. . {being mechanically linked with one another at their distal ends}	9/1095	. . {chemically actuated}
9/0093	. {co-operating with conveyor means}	9/12	. . electric
9/0096	. {co-operating with a working support, e.g. work-table}	9/123	. . . {Linear actuators}
9/02	. characterised by movement of the arms, e.g. cartesian coordinate type ( <a href="#">B25J 9/06 takes precedence</a> )	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 ( <a href="#">in general F15B 15/12</a> )}
		9/16	. Programme controls ( <a href="#">programme controls in general G05B 19/00</a> , e.g. numerical programme controls <a href="#">G05B 19/18</a> ; <a href="#">recording or playback systems G05B 19/42</a> )
		9/1602	. . {characterised by the control system, structure, architecture}

9/1605	. . . {Simulation of manipulator lay-out, design, modelling of manipulator}	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}
9/1607	. . . {Calculation of inertia, jacobian matrixes and inverses}	9/1697	. . . {Vision controlled systems}
9/161	. . . {Hardware, e.g. neural networks, fuzzy logic, interfaces, processor}	9/20	. . fluidic
9/1612	. . {characterised by the hand, wrist, grip control}	<b>11/00</b>	<b>Manipulators not otherwise provided for</b>
9/1615	. . {characterised by special kind of manipulator, e.g. planar, scara, gantry, cantilever, space, closed chain, passive/active joints and tendon driven manipulators}	11/0005	. {Manipulators having means for high-level communication with users, e.g. speech generator, face recognition means}
9/1617	. . . {Cellular, reconfigurable manipulator, e.g. cebot}	11/001	. . {with emotions simulating means}
9/162	. . . {Mobile manipulator, movable base with manipulator arm mounted on it}	11/0015	. . {Face robots, animated artificial faces for imitating human expressions}
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}	11/002	. {Manipulators for defensive or military tasks}
9/1625	. . . {Truss-manipulator for snake-like motion}	11/0025	. . {handling explosives, bombs or hazardous objects}
9/1628	. . {characterised by the control loop}	11/003	. {Manipulators for entertainment}
9/163	. . . {learning, adaptive, model based, rule based expert control}	11/0035	. . {Dancing, executing a choreography}
9/1633	. . . {compliant, force, torque control, e.g. combined with position control}	11/004	. . {Playing a music instrument}
9/1635	. . . {flexible-arm control}	11/0045	. {Manipulators used in the food industry}
9/1638	. . . {compensation for arm bending/inertia, payload weight/inertia}	11/005	. {Manipulators for mechanical processing tasks}
9/1641	. . . {compensation for backlash, friction, compliance, elasticity in the joints}	11/0055	. . {Cutting}
9/1643	. . . {redundant control}	11/006	. . {Deburring or trimming}
9/1646	. . . {variable structure system, sliding mode control}	11/0065	. . {Polishing or grinding}
9/1648	. . . {non-linear control combined or not with linear control}	11/007	. . {Riveting}
9/1651	. . . {acceleration, rate control}	11/0075	. {Manipulators for painting or coating}
9/1653	. . . {parameters identification, estimation, stiffness, accuracy, error analysis}	11/008	. {Manipulators for service tasks}
9/1656	. . {characterised by programming, planning systems for manipulators}	11/0085	. . {Cleaning}
9/1658	. . . {characterised by programming language}	11/009	. . {Nursing, e.g. carrying sick persons, pushing wheelchairs, distributing drugs}
9/1661	. . . {characterised by task planning, object-oriented languages}	11/0095	. {Manipulators transporting wafers}
9/1664	. . . {characterised by motion, path, trajectory planning}	<b>13/00</b>	<b>Controls for manipulators (programme controls <a href="#">B25J 9/16</a>; control in general <a href="#">G05</a>)</b>
9/1666	. . . . {Avoiding collision or forbidden zones}	13/003	. {by means of an audio-responsive input (audible safety signals <a href="#">B25J 19/061</a> )}
9/1669	. . . {characterised by special application, e.g. multi-arm co-operation, assembly, grasping}	13/006	. {by means of a wireless system for controlling one or several manipulators}
9/1671	. . . {characterised by simulation, either to verify existing program or to create and verify new program, CAD/CAM oriented, graphic oriented programming systems}	13/02	. Hand grip control means {(handles or pedals for crane control <a href="#">B66C 13/56</a> ; for measuring the force applied to control members <a href="#">G01L 5/22</a> ; hand-held casings for switching devices, e.g. joy-sticks <a href="#">H01H 9/0214</a> )}
9/1674	. . {characterised by safety, monitoring, diagnostic}	13/025	. . {comprising haptic means}
9/1676	. . . {Avoiding collision or forbidden zones}	13/04	. Foot-operated control means
9/1679	. . {characterised by the tasks executed}	13/06	. Control stands, e.g. consoles, switchboards
9/1682	. . . {Dual arm manipulator; Coordination of several manipulators}	13/065	. . {comprising joy-sticks}
9/1684	. . . {Tracking a line or surface by means of sensors}	13/08	. by means of sensing devices, e.g. viewing or touching devices
9/1687	. . . {Assembly, peg and hole, palletising, straight line, weaving pattern movement}	13/081	. . {Touching devices, e.g. pressure-sensitive}
9/1689	. . . {Teleoperation}	13/082	. . . {Grasping-force detectors (in general <a href="#">G01L 5/16</a> , <a href="#">G01L 5/22</a> )}
9/1692	. . . {Calibration of manipulator}	13/083	. . . . {fitted with slippage detectors}
		13/084	. . . {Tactile sensors (in general <a href="#">G01L 5/16</a> , <a href="#">G01L 5/22</a> )}
		13/085	. . {Force or torque sensors ( <a href="#">B25J 13/082</a> , <a href="#">B25J 13/084</a> take precedence)}
		13/086	. . {Proximity sensors}
		13/087	. . {for sensing other physical parameters, e.g. electrical or chemical properties}
		13/088	. . {with position, velocity or acceleration sensors}

- 13/089 . . . {Determining the position of the robot with reference to its environment}
- 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](#))}**
- 15/0004 . {with provision for adjusting the gripped object in the hand}
- 15/0009 . {comprising multi-articulated fingers, e.g. resembling a human hand}
- 15/0014 . {having fork, comb or plate shaped means for engaging the lower surface on a object to be transported}
- 15/0019 . {End effectors other than grippers}
- 15/0023 . {Gripper surfaces directly activated by a fluid ([flexible fingers \[B25J 15/12\]\(#\)](#))}
- 15/0028 . {with movable, e.g. pivoting gripping jaw surfaces}
- 15/0033 . {with gripping surfaces having special shapes}
- 15/0038 . . {Cylindrical gripping surfaces}
- 15/0042 . . {V-shaped gripping surfaces}
- 15/0047 . {for internally gripping hollow or recessed objects}
- 15/0052 . {multiple gripper units or multiple end effectors}
- 15/0057 . . {mounted on a turret}
- 15/0061 . . {mounted on a modular gripping structure}
- 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