

Adhesive applicator and object placing head incorporating the same**Technical Field**

[0001] This invention relates to construction, and in particular the building of constructions utilising objects which are cemented or adhered together. In particular, this invention relates to an adhesive applicator and a head for placing objects incorporating such an adhesive applicator.

Background Art

[0002] The following discussion of the background art is intended to facilitate an understanding of the present invention only. It should be appreciated that the discussion is not an acknowledgement or admission that any of the material referred to was part of the common general knowledge as at the priority date of the application.

[0003] The inventor previously described a brick laying machine in US patent 8,166,727. An early prototype brick laying machine, based on that described in US patent 8,166,727, and built by the inventor, resulted in the development of various brick laying heads and adhesive application arrangements. These included a brick laying and adhesive applying head that had a single combined brick laying gripper and applicator to apply adhesive to a surface on which bricks were to be laid. This arrangement slowed the process, since the head had to first apply the adhesive before it could access and place a brick. There was also a disadvantage in that the application of adhesive to a vertical surface to connect adjacent bricks was problematic.

[0004] US patent 8,166,727 also described a double arm laying head, where a first arm applied adhesive to the previous course and a second arm laid a brick on the previously applied adhesive. This was found to require complex programming to avoid collisions between the two arms and also required serial activity in that the adhesive is applied in the area to be laid and then the brick is laid subsequently. There was however, a productivity advantage over a single combined brick laying gripper and applicator that must apply adhesive and then lay a brick.

[0005] The inventor considered and tested application of adhesive by moving a nozzle in a vertical direction to apply adhesive to the vertical face of a brick presented by the chain conveyor described in US patent 8,166,727. The main problem encountered with this approach was that gravity exerts a downward force on the adhesive, which means

that adhesive drips from the nozzle or falls off the brick before tacking onto the brick. It is effective for adhesives that can be sprayed. However in an outside environment, wind tends to cause spray to drift or form "overspray" which creates a mess. Adhesive application onto bricks being chain conveyed down the boom was also considered, but the difficulty with this was that as the boom angle changes, the application angle changes and when the boom or brick is vertical, the same problems of applying adhesive to a vertical brick are encountered.

[0006] It is therefore, an object of this invention to provide an arrangement for application of adhesive in a brick laying machine, in a manner that overcomes these disadvantages. It is also an object to provide an adhesive applicator that can provide a compact arrangement to co-locate with a brick laying head, to minimise interference with the movement of the brick laying head.

[0007] Throughout the specification unless the context requires otherwise, the word "comprise" or variations such as "comprises" or "comprising", will be understood to imply the inclusion of a stated integer or group of integers but not the exclusion of any other integer or group of integers.

[0008] In this specification the word "brick" is intended to encompass any building element such as a brick or block, to be placed during the construction of a building or wall or the like.

Summary of Invention

[0009] In accordance with the invention there is provided an adhesive applicator tool for machine application of adhesive, said adhesive applicator tool comprising an adhesive applicator head having at least one nozzle fed with adhesive under pressure for selective application to a surface, said adhesive applicator head being supported on a distal end of a tongue member, said tongue member being housed in a sheath for linear movement to extend said adhesive applicator head across said surface for application of adhesive, and retract said tongue within said sheath to withdraw said adhesive applicator head away from said surface, said tongue being rigid when extended obliquely or horizontally and freely deflectable in only one dimension upwardly, about horizontal axes. The tongue is freely deflectable upwardly but not from side to side, much in the same way as a human finger is moveable, palm facing up. This restriction in movement allows controlled application of adhesive to a surface,

which typically will be disposed horizontally. Particularly it allows the adhesive applicator head to be moved linearly relative to the surface, in a controlled manner.

[0010] Preferably said sheath has a tip which is, in use located aligned horizontally, so that said tongue extends horizontally from the tip of said sheath.

[0011] Preferably said sheath curves upwardly from said tip, with the tongue being freely deflectable about horizontal axes allowing the tongue to move within said sheath.

[0012] Preferably said tongue is configured as a chain-link-type actuator, said chain-link-type actuator being linearly moveable by a driven sprocket to selectively extend and retract said tongue from said tip of said sheath.

[0013] Preferably said chain link type actuator comprises a chain having body portions attached to one side, said body portions having ends that contact ends of adjacent body portions preventing said chain folding about said horizontal axes in one direction away from a horizontal alignment of said chain.

[0014] Preferably said tongue comprises a plurality of body portions, each body portion having on a top surface at least one pivot mount with a transverse aperture extending horizontally therethrough to provide a connection point for a chain link to an adjacent said pivot mount of an adjacent said body portion, each said body portion having opposed ends that contact ends of adjacent body portions, said tongue being foldable in one direction only about said transverse apertures, the opposed ends of adjacent body portions coming into contact preventing said tongue folding about said connection points in the opposite direction.

[0015] Preferably each said body portion has a channel extending longitudinally therethrough, for routing services such as wiring and tubing for the transport of adhesive to said adhesive applicator. The channel may be an inverted u-channel with the pivot mounts being located on top of the web.

[0016] Preferably the channel is closed, to fully enclose said services extending longitudinally through said tongue.

[0017] Preferably there are two said pivot mounts located on top of each said body portion, one said pivot mount located near each opposed end of said body portion.

[0018] Preferably on each body portion, said pivot mounts are spaced apart from each other by the same longitudinal distance as the sum of the longitudinal distances from

each to the closest end of said body portion. In this manner, the pivot mounts can form teeth of a cog on top of the assembled tongue, to be engaged by a driven sprocket to selectively extend and retract said tongue from said tip of said sheath.

[0019] Preferably the angle of the faces forming the ends of each said body portion relative to the longitudinal extent of the body portion add up to 180 degrees. Most preferably the face forming each end of each said body portion is at right angles relative to the longitudinal extent of the body portion. With either arrangement, the tongue can extend outward and be self supporting, and bendable upward only, about the chain links that interconnect them.

[0020] Also in accordance with the invention, there is provided a brick laying and adhesive applying head for a brick laying machine, said brick laying and adhesive applying head having a clevis with a horizontal axis for pivot mounting for controlled rotation to the remote end of a boom, said brick laying and adhesive applying head including a pivotable clamp to receive and clamp a brick presented at the remote end of said boom, said pivotable clamp being pivotally mounted about said horizontal axis; said brick laying and adhesive applying head supporting an adhesive applicator tool comprising an adhesive applicator head having at least one nozzle fed with adhesive under pressure for selective application to a surface of a brick, said adhesive applicator head being supported on a distal end of a tongue member, said tongue member being housed in a sheath for linear movement to extend said adhesive applicator across a brick presented by said pivotable clamp, and retract said tongue within said sheath to withdraw said adhesive applicator away from said pivotable clamp, said tongue being rigid when extended obliquely or horizontally and freely deflectable in only one dimension upwardly about horizontal axes away from said horizontal axis only (i.e. freely deflectable upwardly but not from side to side, much in the same way as a human finger is moveable, palm facing up); said brick laying and adhesive applying head having a brick laying head mounted thereto by a mount located in a position away from said clevis, said brick laying head having a brick laying clamp moveable between a position to receive and clamp a brick held by said pivotable clamp, to a position in which said brick is released and laid; said sheath extending away from said horizontal axis, and substantially along said clevis toward said mount, to provide clearance between said sheath and said brick laying head in order to allow operation without interference.

[0021] Preferably said sheath has a tip which is, in use located horizontally, so that said tongue extends horizontally from the tip of said sheath.

[0022] Preferably said sheath curves upwardly to extend between said mount and said second horizontal axis, and the tongue being freely deflectable about horizontal axes allows the tongue to move within said sheath.

[0023] Preferably said tongue is configured as a chain-link-type actuator, said chain-link-type actuator being linearly moveable by a driven sprocket to selectively extend and retract said tongue from said tip of said sheath.

[0024] Preferably said chain link type actuator comprises a chain having body portions attached to one side, said body portions having ends that contact ends of adjacent body portions preventing said chain folding about said horizontal axes in one direction away from a horizontal alignment of said chain.

[0025] Preferably said tongue comprises a plurality of body portions, each body portion having on a top surface at least one pivot mount with a transverse aperture extending horizontally therethrough to provide a connection point for a chain link to an adjacent said pivot mount of an adjacent said body portion, each said body portion having opposed ends that contact ends of adjacent body portions, said tongue being foldable in one direction only about said transverse apertures, the opposed ends of adjacent body portions coming into contact preventing said tongue folding about said connection points in the opposite direction.

[0026] Preferably each said body portion has a channel extending longitudinally therethrough, for routing services such as wiring and tubing for the transport of adhesive to said adhesive applicator. The channel may be an inverted u-channel with the pivot mounts being located on top of the web.

[0027] Preferably the channel is closed, to fully enclose said services extending longitudinally through said tongue.

[0028] Preferably there are two said pivot mounts located on top of each said body portion, one said pivot mount located near each opposed end of said body portion.

[0029] Preferably on each body portion, said pivot mounts are spaced apart from each other by the same longitudinal distance as the sum of the longitudinal distances from each to the closest end of said body portion. In this manner, the pivot mounts can form teeth of a cog on top of the assembled tongue, to be engaged by a driven sprocket to selectively extend and retract said tongue from said tip of said sheath.

[0030] Preferably the angle of the faces forming the ends of each said body portion relative to the longitudinal extent of the body portion add up to 180 degrees. Most preferably the face forming each end of each said body portion is at right angles relative to the longitudinal extent of the body portion. With either arrangement, the tongue can extend outward and be self supporting, and bendable upward only, about the chain links that interconnect them.

[0031] Preferably the brick laying head includes a spherical geometry robot.

[0032] Preferably said brick laying head includes a linearly extendable arm depending downward, attached about a mount roll-axis to said mount, said mount roll-axis allowing controlled roll motion in said arm relative to said mount, said brick laying clamp being mounted for controlled motion to the end of said linearly extendable arm about a universal joint allowing controlled pitch motion and controlled roll motion in said brick laying clamp relative to said arm, and said brick laying clamp is mounted to said universal joint on a rotatable mount for controlled rotation about a yaw axis.

[0033] The mount roll-axis will normally be longitudinal relative to the extent of the boom that the brick laying and adhesive applying head is attached to, and disposed horizontally in normal operation, as controlled by a ram or the like that controls the pose of the brick laying and adhesive applying head relative to the remote end of the foldable boom.

[0034] Preferably said mount includes a mount pitch-axis allowing controlled pitch motion of said arm relative to said mount. The mount pitch-axis runs transverse to the longitudinal extent of the linearly extendable arm.

[0035] Preferably said universal joint has a first wrist-axis pivotable transverse to the longitudinal extent of said arm and a second wrist-axis disposed normal to said first wrist axis, both wrist-axes being normal to said yaw axis.

[0036] Preferably said linearly extending arm includes a linear guide which connects with said mount for controlled linear movement to extend and retract said arm in order to move said brick laying clamp toward or away from said mount.

[0037] Preferably the brick laying clamp includes jaws that are independently moveable to clamp and unclamp a brick, and also selectively moveable in unison to offset the position of the jaws relative to the brick laying clamp. This allows the brick laying clamp to access a position to lay a brick, that may be up against an existing wall lying alongside one of the jaws of the brick laying clamp.

[0038] Also in accordance with the present invention there is provided a brick laying and adhesive applying head for a brick laying machine, said brick laying and adhesive applying head having a clevis with a horizontal axis for pivot mounting for controlled rotation to the remote end of a boom, said brick laying and adhesive applying head including a pivotable clamp to receive and clamp a brick presented at the remote end of said boom, said pivotable clamp being pivotally mounted about said horizontal axis; said brick laying and adhesive applying head supporting an adhesive applicator tool aligned to extend said adhesive applicator across a brick presented by said pivotable clamp; said brick laying and adhesive applying head having a brick laying head mounted thereto by a mount located in a position away from said clevis, said brick laying head having a brick laying clamp moveable between a position to receive and clamp a brick held by said pivotable clamp, to a position in which said brick is released and laid.

[0039] Preferably the brick laying head includes a spherical geometry robot.

[0040] Preferably said brick laying head includes a linearly extendable arm depending downward, attached about a mount roll-axis to said mount, said mount roll-axis allowing controlled roll motion in said arm relative to said mount, said brick laying clamp being mounted for controlled motion to the end of said linearly extendible arm about a universal joint allowing controlled pitch motion and controlled roll motion in said brick laying clamp relative to said arm, and said brick laying clamp is mounted to said universal joint on a rotatable mount for controlled rotation about a yaw axis.

[0041] Preferably said mount includes a mount pitch-axis allowing controlled pitch motion of said arm relative to said mount.

[0042] Preferably said universal joint has a first wrist-axis pivotable transverse to the longitudinal extent of said arm and a second wrist-axis disposed normal to said first wrist axis, both wrist-axes being normal to said yaw axis.

[0043] Preferably said linearly extending arm includes a linear guide which connects with said mount for controlled linear movement to extend and retract said arm in order to move said brick laying clamp toward or away from said mount.

[0044] Preferably the brick laying clamp includes jaws that are independently moveable to clamp and unclamp a brick, and also selectively moveable in unison to offset the position of the jaws relative to the brick laying clamp.

[0045] Preferably the brick laying and adhesive applying head as described above incorporates the with tongue and sheath as described above, wherein said adhesive applicator tool is configured to retract said tongue within said sheath to withdraw said adhesive applicator away from said pivotable clamp, and said sheath is aligned extending away from said horizontal axis, and substantially along said clevis toward said mount, to provide clearance between said sheath and said brick laying head in order to allow operation without interference.

Brief Description of Drawings

[0046] A preferred embodiment of the invention comprising a brick laying and adhesive applying head incorporated into an automated brick laying machine, will now be explained in the following description made with reference to the drawings, in which:

Figure 1 shows a view of the automated brick laying machine 2 with its truck base 1 with the boom and stick assembly 141 unfolded.

Figure 2 shows a view of the automated brick laying machine 2 with the boom and stick assembly 141 folded and stowed for driving on a public road.

Figure 3 shows a site plan of the automated brick laying machine 2 set up near a concrete slab 136 on which the automated brick laying machine 2 will build a structure not shown.

Figure 4 shows a cross section through the first stick 15 and second stick 17.

Figure 5 shows a side view of the brick laying and adhesive applying head 32.

Figure 6 shows a plan view and schematic diagram of the glue application system 150.

Figure 7 shows a view of the carousel 48.

Figure 8 shows a view of the tower 10.

Figure 9 shows a side view cross section of first boom 12.

Figure 10 shows an end view cross section of first boom 12.

Figure 11 shows a view of first boom 12.

Figure 12 shows a view of shuttle-B1 224.

Figure 13 shows a side view of shuttle-B1 224.

Figure 14 shows a view of the tip end of boom 12 and a drive assembly 254.

Figure 15 shows a view of the tower – first boom (T-B1) rotator 271 and the tower 10 and first boom 12.

Figure 16 shows a view of the tower – first boom (T-B1) rotator 271.

Figure 17 shows a view of the second boom 14.

Figure 18 shows a view of the second end 526 of second boom 14.

Figure 19 shows a view of the second end 526 of second boom 14.

Figure 20 shows a cross section side view of the second end 526 of second boom 14.

Figure 21 shows a view of the first end 525 of second boom 14.

Figure 22 shows a view of the rotator-B2-S1 548.

Figure 23 shows a view of the first stick 15.

Figure 24 shows a view of the first end 561 of the first stick 15.

Figure 25 shows a view of the second stick 17.

Figure 26 shows a view of the first end 598 of the second stick 17.

Figure 27 shows a view of the second end 599 of the second stick 17.

Figure 28 shows a view of the third stick 18.

Figure 29 shows a view of the first end 618 of the third stick 18.

Figure 30 shows a view of the second end 619 of the third stick 18.

Figure 31 shows a view of the fourth stick 19.

Figure 32 shows a view of the first end 637 of the fourth stick 19.

Figure 33 shows a view of the second end 638 of the fourth stick 19.

Figure 34 shows a view of the fifth stick 20.

Figure 35 shows a view of the first end 657 of the fifth stick 20.

Figure 36 shows a view of the second end 658 of the fifth stick 20.

Figure 37 shows a view of the second end 658 of the fifth stick 20.

Figure 38 shows a view of the flipper assembly 687.

Figure 39 shows a view of the flipper assembly 687.

Figure 40 shows a view of the brick laying and adhesive applying head 32.

Figure 41 shows a view of the first boom 12.

Figure 42 shows a cut-away view of first boom 12 and second boom 14.

Figure 43 shows a side view of the boom assembly 732 showing internal cable chains.

Figure 44 shows a side view of the boom assembly 732 showing internal cable chains.

Figure 45 shows a side view of the boom assembly 732 showing internal cable chains.

Figure 46 shows a view of the stick assembly 744 showing extension cable.

Figure 47 shows a view of the stick assembly 744 showing retraction cable.

Figure 48 shows a view of the stick assembly 744 showing retraction cables.

Figure 49 shows a view of the adhesive applicator 777.

Figure 50 shows a view of the sliding chain 114.

Figure 51 shows a view of a hollow chain link 778.

Figure 52 shows a top view of straight guide 784.

Figures 53 and 53A show a side view of the brick laying and adhesive applying head 32 and fifth stick 20.

Figures 54A – 54E show side views of the foldable boom in various poses.

Figures 55A – 55F show a sequence of a brick being transferred from the tower 10 to the T-B1 rotator 271 to first boom 12.

Figures 56A – 56G show a sequence of a brick being transferred from the second boom 14 to the B2-S1 rotator 548 to the first stick 15. In the figures 56A to 56G the foldable boom 732 is in a bent pose.

Figures 57A – 57D show a sequence of a brick being transferred from the second boom 14 to the B2-S1 rotator 548 to the first stick 15. In the figures 57A to 57D the foldable boom 732 is in a horizontal pose.

Figures 58A – 58Q show a sequence of a brick being transferred from the fifth stick 20, to the S5-H flipper 687, having adhesive applied to the brick, then the brick being transferred to the laying gripper 44 and being laid.

Figure 59 shows a close up of the tower shuttle 186 at the top of tower 10.

Figure 60 shows a side view of first boom element 12 and in particular the transfer of a brick from shuttle-B1 224 to shuttle-B2 531.

Figure 61 shows a cut away view of part of the brick laying and adhesive applying head and showing the mounting of the brick laying head.

Figure 62 shows a further view of part of the brick laying and adhesive applying head and showing the mounting of the brick laying head.

Figure 63 shows a cut away view of part of the brick laying head.

Description of Embodiments

[0047] The embodiment is directed toward a brick laying and adhesive applying head 32 which is fitted to an articulated telescopingly extendable boom mounted on a truck, forming an automated brick laying machine. Referring to figure 1, a truck 1 supports a brick laying machine 2 which is mounted on a frame 3 on the chassis (not shown) of the truck. The frame 3 provides additional support for the componentry of the brick laying machine 2 beyond the support that would be provided by a typical truck chassis. Individual bricks are placed on a carousel 48, which is located coaxially with a tower 10, at the base of the tower 10. The carousel 48 has a gripper mounted thereon which receives a brick. The carousel 48 transfers the brick via the tower 10 to an articulated (folding about horizontal axis 16) telescoping boom comprising first boom element in the form of telescopic boom 12, 14 and second boom element in the form of telescopic stick 15, 17, 18, 19, 20. Each element 12, 14, 15, 17, 18, 19, 20 of the folding telescoping boom has a shuttle located inside on a longitudinally extending track in the element, to transport a brick along the longitudinal extent of the element. The bricks are moved through the inside of the folding telescoping boom by the linearly moving shuttles. The shuttles are equipped with grippers that pass the brick from shuttle to shuttle. Referring to figure 4, elements 15 and 17 are shown, showing tracks 25 supporting shuttle 26 running along the length of element 17, and showing tracks 29 supporting shuttle 30 running along the length of element 15. Shuttle 26 has jaws 27 and shuttle 30 has jaws 31, which alternately can grip a brick 298. When the shuttles 27 and 30 are coincident both sets of jaws 27 and 31 can grip the brick 298 as the brick is passed from one shuttle 26 to the other shuttle 30.

[0048] The end of the boom is fitted with a brick laying and adhesive applying head 32. The brick laying and adhesive applying head 32 mounts by pins (not shown) to element 20 of the stick, about an axis 33 which is disposed horizontally. The poise of the brick laying and adhesive applying head 32 about the axis 33 is adjusted by double acting hydraulic ram 35, and is set in use so that the base 811 of a clevis 813 of the robotic arm 36 mounts about a horizontal axis, and the tracker component 130 is

disposed uppermost on the brick laying and adhesive applying head 32. The brick laying and adhesive applying head 32 applies adhesive to the brick and has a robot that lays the brick. Vision and laser scanning and tracking systems are provided to allow the measurement of as-built slabs, bricks, the monitoring and adjustment of the process and the monitoring of safety zones.

[0049] For ease of understanding, headings will be used in the following discussion.

Truck

[0050] Referring again to figure 1, a vehicle in the form of a rigid body truck 1 is used as a base for the automated brick laying machine 2. In the preferred embodiment the truck 1 is a 8x8, 8x6 or 8x4 rigid body truck manufactured for example by Volvo, Mercedes, Iveco, MAN, Isuzu or Hino. The truck has a typical driver's cabin 54. In an alternative arrangement, a semi-trailer intended for connection to a prime mover using a fifth wheel, may be used instead of a rigid body truck. The brick laying machine 2 could be mounted on a trailer, but this removes the convenience of having it truck mounted.

Frame

[0051] A frame 3 forming a rigid chassis is mounted to the truck. The frame 3 supports a pair of forward legs 4 and a pair of aft legs 5, one of each pair on each side of the truck. The legs 4 and 5 can telescopically extend outwardly, and hydraulic rams then push down feet 6 to provide stability to the automated brick laying machine 2. In practice, the hydraulic rams will adjust by positioning the feet 6 so that the frame 3 and hence the rigid body truck 1 is positioned horizontally. This results in correct vertical alignment of the vertical axis 9 and the tower 10 which are described hereafter. It follows then, that this correct alignment ensures that, subject to deflection tolerances, the axis 33 at the end of the element 20 is horizontal, and then with correct adjustment of the poise of the brick laying and adhesive applying head 32 by the ram 35, the base 811 of a clevis 813 of the robotic arm 36 mounts about a horizontal axis, and the tracker component 130 is disposed uppermost on the brick laying and adhesive applying head 32.

[0052] An enclosure 7 forming an outer body is mounted to the frame 3. The enclosure 7 provides some weather protection, noise isolation and guarding of moving parts. Referring to figures 1, 2 and 6, the enclosure 7 is fitted with a pair of doors 85, 86 that are open when the boom 12 and stick 15 are folded. When the boom 12 and

stick 15 are unfolded, the top doors 85, 86 are closed by moving door 85 to the right 87 and door 86 to the left 88 to provide a first level of rain protection and noise isolation.

Carousel

[0053] Refer to figures 1, 7 and 8. Referring to figure 1, the folding boom 732 can be rotated about a vertical axis 9 to point in any direction away from the truck. Referring to figures 1 and 2, the carousel 48 receives bricks, one at a time, at a location approximately on the centreline of the truck, behind the tower 10, and rotates about a vertical axis 9 to line the bricks up with the rotated folding boom 732.

[0054] Referring to figures 7 and 8, the carousel 48 receives a brick from the transfer robot 64 and passes it to a tower shuttle 186 sliding on the tower 10. Referring to figure 7, the carousel 48 is shown in greater detail. The carousel has a ring frame 166 which rotates around the tower 10 (shown in figure 8). The ring frame 166 supports a gripper 74 that can tilt to receive a brick from the transfer robot 64 and then be rotated to line up with the tower shuttle 186. A detailed description follows.

[0055] Referring to figure 7, the frame 3 supports a ring guide 167 which supports a plurality of rollers 169 that in turn support the ring frame 166 which is thus able to rotate about the vertical slewing axis 9. The ring frame 166 supports a bracket 170 that in turn supports an arm 165 that rotates about a horizontal rotary axis 77. The arm 165 supports the gripper 74 which has jaws 171, 172 that move toward each other to hold a brick (not shown), or apart to release the brick. The ring frame 166 is rotated about the vertical axis 9 by a servo motor 173 and gearbox 174 that drives a pinion 175 engaged with a ring gear 176 fixed to the ring guide 167. The bracket 170 supports a servo motor 177 that drives a gearbox 178 which moves the arm 165. The arm 165 supports a servo motor 179 and a lead screw 180. The servo motor 179 rotates the lead screw 180. The jaws 171, 172 are respectively fitted with lead nuts not shown that engage with the lead screw 180. The ring frame 166 supports a cable duct 185.

[0056] The frame 3 supports a cable guide 181. The cable guide 181 supports a cable chain 182. The cable chain 182 is connected at a first end 183 to the cable guide 181 and is therefore fixed relative to the frame 3. The cable chain 182 has a second end 184 attached to the cable duct 185. Electric current carrying cables (not shown) that carry power and control signals and sensor signals from the electric control cabinet 82,

are routed via the frame 3, through the cable chain 182 to the cable duct 185 and then to the servo motors 173, 177, 179.

[0057] The carousel 48 can move the gripper 74 from a pickup position where it receives a brick, and rotate to a drop off position where it deposits the brick to the gripper jaws 207, 208 on the tower shuttle 186 (shown on figure 8).

Tower

[0058] Referring to figure 8, the frame 3 supports a slewing ring 11 at its front end 78, located coaxially with the carousel 48. The slewing ring 11 supports a turret in the form of a tower 10. The tower 10 can slew about the vertical axis 9 of the slewing ring 11. The tower 10 supports the foldable boom 732 (shown in figure 1). The tower supports a tower shuttle 186 that moves bricks from the carousel 48 at the bottom end of the tower to the foldable boom 732 at the top of the tower 10.

[0059] Refer to figure 8 and figure 59. The tower 10 supports two parallel spaced linear bearing rails 189, 190. The linear bearing rails 189, 190 respectively support four bearing cars 191 and 192 (and others occluded, not shown). The bearing cars 191, 192 support a tower shuttle car 193 which in turn supports a gripper 194. The gripper 194 may grasp a brick 195. The tower 10 supports a servo motor 196 which drives a toothed pulley 197 that engages with and drives a belt 198 that is connected to, and thereby drives the tower shuttle 186 in a vertical direction. The tower 10 supports a servo motor 199 that drives a toothed pulley 200 that engages and drives a toothed belt 201. Tower 10 supports an upper idler pulley 202. Toothed belt 201 wraps around upper idler pulley 202. The tower shuttle car 193 supports pulleys 203 and 204. The tower shuttle car 193 supports a lead screw 206. Leadscrew 206 is connected to a pulley 205. The toothed belt 201 passes around pulley 203, then drives pulley 205 and thus drives the lead screw 206. The belt 201 passes around pulley 204 and then returns to pulley 200. The tower shuttle car 193 slideably supports gripper jaws 207, 208. Gripper jaws 207, 208 support lead screw nuts (not shown) that engage leadscrew 206. Leadscrew 206 moves jaws 207, 208 toward each other to grip a brick 195, and in the opposite rotational direction, moves jaws 207, 208 apart to release the brick 195.

[0060] Refer to figure 8. The tower 10 supports a lug 209 with a bore 213 having a horizontal axis 214, the bore receiving a fastener to connect an end of hydraulic ram 22 (shown in figure 1) to control the pose of the first boom 12. Tower 10 supports clevis

plates 210, 211 which have a bore 212 with a horizontal axis 13, about which the near end of the first boom is attached for pivoting movement (shown in figure 1).

Boom

[0061] Refer to figure 1. The foldable boom 732 is articulated and telescopic so that it can position the laying head throughout a large working volume, far from and close to the truck, both low and high so that the laying head can reach all courses of the structure to be built, both near and far, low and high. Figure 54A shows the foldable boom 732 in a folded pose for transport. Figure 54B shows the foldable boom 732 with the first boom 12 raised and the stick assembly 744 vertical. Figure 54C shows the foldable 732 with the stick assembly 744 horizontal with the telescopic sections extended. Figure 54C shows a pose that could be used to build a multi storey structure. Figure 54D shows the foldable boom assembly 732 with the first boom 12 raised above horizontal and the stick assembly 744 lowered slightly below horizontal. Figure 54E shows the foldable boom 732 at its maximum extension with both the first boom 12 horizontal and the stick assembly 744 horizontal.

[0062] The foldable boom 732 allows motion through a big envelope free of singularities and poles. A pole is a position within a robot's envelope that requires rapid rotation of one or more robot joints to maintain consistent orientation of the end effector, for the end effector to pass along a trajectory that passes through the pole. A singularity is a position or orientation, or a set of positions and orientations within the envelope that cannot be reached, or where the joints of the robot become poorly behaved, unstable, or the joint positions are difficult to calculate. Normal industrial robots typically complete the same task over and over so that it is possible to design, or alter the trajectory and robot pose to be free and clear of poles and singularities or to pass through a pole with specified rotation of the pole axis. The automated brick laying machine however must be able to complete a variety of tasks and any particular structure will require the boom to move through a large portion of its envelope, thus making a pole and singularity free working envelope desirable.

[0063] Shuttles within each section of the boom transport a brick along the inside of the boom. Shuttles pass a brick from a previous shuttle to the next. Rotators at each articulated joint of the boom move a brick from one boom element to the next, passing the brick from a previous adjacent shuttle to the next adjacent shuttle.

[0064] The bricks are passed by the shuttles, through the inside of the boom. The bricks are moved through the inside of the boom so that the boom structure contains

the bricks and/or debris, in the unlikely event that a brick, or debris from a brick becomes loose from a shuttle. The boom structure provides convenient support to mount shuttles opposite each other. In the present invention within the telescoping elements of the boom and within the telescoping elements of the stick, the shuttles are alternately mounted above or below the brick, so that adjacent shuttles may move so that the grippers on the shuttles can both grasp a brick simultaneously and thereby transfer a brick from one shuttle to the next, without letting go of the brick. Figure 60 shows a partial view of the inside of the first boom element comprising first boom 12 and second boom 14, with shuttle-B1 224 gripping a brick 28 from below and shuttle-B2 531 gripping a brick from above. The invention could alternately be arranged to support the shuttles from the sides of the boom. The invention could alternately be arranged to support the shuttles on the top of the boom, however it would then be desirable to fit an additional enclosure to boom to contain any dropped bricks or debris and the overall size of the boom would be larger or less structurally stiff.

First Boom Element

[0065] Referring to figures 1 and 17, the tower 10 pivotally supports a foldable boom on clevis plates 210 and 211 for rotation about horizontal axis 13. The foldable boom comprises a first boom element comprising first boom 12 and telescoping second boom 14, and a second boom element comprising stick assembly 744. First boom 12 can pivot about the horizontal axis 13 at the top of the tower 10, and a sliding second boom 14 is telescopically able to slide within the first boom 12.

Second Boom Element

[0066] Referring to figure 1, the second boom element 744 is pivotally connected about a horizontal axis 16 by an element in the form of an articulating first stick 15 to the distal end of the second boom 14. The axis 16 is substantially parallel to the horizontal articulation axis 13 of the first boom.

[0067] A sliding second stick 17 is telescopically able to slide within the first stick 15. A sliding third stick 18 is telescopically able to slide within the second stick 17. A sliding fourth stick 19 is telescopically able to slide within the third stick 18. A sliding fifth stick 20 is telescopically able to slide within the fourth stick 19. Collectively first stick 15, second stick 17, third stick 18, fourth stick 19 and fifth stick 20 form a stick assembly 744 also referred to as the second boom element.

[0068] The number of telescopic booms 12, 14 or sticks 15, 17, 18, 19, 20 could be altered without deviating from the inventive concepts described. Collectively the tower 10, booms 12, 14 and sticks 15, 17, 18, 19, 20 form a foldable boom assembly 732.

[0069] First boom 12 has a first near end 269 and a second distal end 270 shown in figure 9. First boom 12 is connected to the tower 10 (shown in figure 8) by a pin or pins not shown, through the bore 212, in clevis plates 210 and 211, connecting through apertures in first boom located at its near end 269.

[0070] Lug 209 on the tower 10 is connected to the rod end of ram 22 by a pin (not shown). Ram 22 supports a trunnion mount 215 located a short distance along the first boom 12 from the near end 269. The trunnion mount 215 provides boom lift lugs 216, 217. The articulated joint 21 of the tower 10 to the boom 12 about axis 13 is moved by ram 22 powered by electricity or hydraulics.

Rotator

[0071] Refer to figure 15 and figure 16. The tower 10 supports a brick rotating mechanism in the form of T-B1-rotator 271. The T-B1-rotator 271 is used transfer a brick from the tower shuttle 186 to the first boom shuttle 224 (shown in figure 10, 12 and 55D). Figure 55A shows the tower shuttle 186 holding brick 298. Figure 55B shows the brick held by the T-B1-rotator 271 after receiving it from the tower shuttle 186. Figure 55C shows the T-B1-rotator 271 moving to align itself with the first boom segment 12. Figure 55D shows the T-B1-rotator 271 aligned with the first boom segment and shuttle-B1 224 moving into position under brick 298. It should be understood that the boom will not necessarily be horizontal while this process occurs. Figure 55E shows the shuttle-B1 224 in position under the brick 298. In this position the shuttle-B1 224 will grip the brick and the T-B1-rotator 271 will release the brick. Figure 55F shows the brick 298 held by the shuttle-B1 224 moving up the first boom segment 12. Figure 55G shows the T-B1-rotator 271 moving into position to accept another brick from the tower shuttle 186.

[0072] A detailed description of the T-B1-rotator follows.

[0073] Referring to figure 16, T-B1-rotator 271 has a bracket 272 which is fastened to the tower 10 (shown in figure 8). Bracket 272 supports a spacer 274 which supports a servo motor 273. Servo motor 273 drives a pulley 275. Bracket 272 supports idler pulleys 276, 277 and a bearing reducer 278. Bearing reducer 278 is fitted with an input shaft 279 which is fitted with a pulley 280 driven by servo motor 273 via an

endless toothed belt 281 wrapped around pulleys 275, 276, 277 and 280. Arm 282 is rotated by bearing reducer 278 about a horizontal axis 290.

[0074] Bearing reducer 278 supports an arm 282 having a plate 283 depending therefrom at right angles. Plate 283 supports linear guides 284, 285. Linear guides 284, 285 respectively support bearing cars 286, 287 which respectively support jaws 288, 289 provided to clamp a brick. Jaws 288, 289 respectively are fitted with lead screw nuts 296, 297 shown as hidden lines. Leadscrew nuts 296, 297 engage with leadscrew 293.

[0075] Arm 282 supports a servo motor 291 (not shown clearly in figure 16, but shown in figure 15) which drives a pulley 292. Arm 282 supports a leadscrew 293 fitted with a pulley 294. An endless toothed belt 295 is wrapped around pulleys 292 and 294. Through this arrangement, servo motor 291 drives leadscrew 293 which is engaged with leadscrew nuts 296, 294 to move jaws 288, 289 together to grip a brick 298 or apart to release the brick 298.

[0076] As can be seen in the drawings, and particularly in the sequence of figures 55A to 55G, the brick 298 is transported up the tower 10 with its longitudinal extent parallel with the vertical axis 9 of the tower 10. The tower shuttle 186 holds the brick 298 in its gripper jaws 207 and 208 vertically above the body of the tower shuttle car 193, so that the brick can be passed within reach of the jaws 288, 289 of T-B1-rotator 271. The T-B1-rotator 271 rotates the brick 298 so that its longitudinal extent is aligned with the longitudinal extent of boom 12 (and 14). The T-B1-rotator 271 rotates about the same horizontal axis 13 as first boom 12 is mounted to the tower 10. The location of this horizontal axis 13 is such that the shuttle-B1 224 is able to travel under the T-B1-rotator 271 to allow the transfer of the brick 298 from T-B1-rotator 271 to the shuttle-B1 224.

First Boom

[0077] Refer to figures 9, 10 and 11. Referring to figure 9 first boom 12 has boom lift lugs 216, 217 welded thereto. Referring to figure 10, boom 12 is of a substantially rectangular or box cross section, and is constructed by welding bottom plate 218 to side plates 219, 220 which are welded to top plate 221. Removable panels (not shown) may be provided in convenient positions along any of the plates 218, 219, 220, 221, to provide access for servicing of internal componentry within first boom 12. The bottom plate 218 supports a track in the form of channels 222, 223 (also shown in figure 9).

Channels 222 and 223 support shuttle-B1 224. Referring to figure 9, shuttle 224 is shown gripping a brick 225.

Shuttle

[0078] A shuttle grips a brick and is moved along the inside of the boom from the near end of the boom, nearly to the distal end of the boom, by toothed belts driven by servo motors fitted to the boom. The servo motors are fitted to the boom to minimise the size and weight of the moving shuttle and also to avoid having to use cable chains or slip tracks to transfer electrical power and signals to and from the shuttles. One servo motor 256 moves the shuttle and the other servo motor 255 moves the jaws of the shuttle. A detailed description follows.

[0079] Refer to figures 9, 10 and 14. Referring to figure 14, bottom plate 218 supports a drive assembly 254 located at the distal end 270 of the first boom 12. Drive assembly 254 has a body that supports servo motors 255 and 256. Servo motor 255 drives a pulley 258 which drives an endless belt 251. Endless belt 251 passes around idlers 260, 261. Plate 218 supports idler pulley assembly 259 (shown in figure 9) to turn the belt.

[0080] Servo motor 256 drives a pulley 257. Drive assembly 254 has a shaft 262 that supports a large pulley 263 and a small pulley 264, forming part of a reduction drive. An endless toothed belt 258 wraps around pulley 257 and large pulley 263. A belt 266 wraps around pulley 264 and idler pulley assembly 265 at the near end 269 of first boom. Belt 266, running the length of first boom 12 is driven by pulley 264.

[0081] Refer to figures 9, 12 and 13. Referring to figure 12, shuttle-B1 224 has a body 246 which supports wheels 226, 227, 228, 229 that rotate about substantially horizontal axes, and supports wheels 230, 231, 232, 233 that rotate about axes in a vertical plane. Shuttle-B1 224 supports linear guides 234, 235. Linear guides 234, 235 respectively support bearing cars 236, 237 which respectively support jaws 238, 239. Jaw 238 is provided with rubber gripping pads 240, 241 and jaw 239 is provided with rubber gripping pads 242, 243. Jaws 238, 239 respectively support lead screw nuts 244, 245 at the base thereof (shown in figure 13). Body 246 supports bearing housings 247, 248 (shown in figure 13) which support a leadscrew 249. Referring to figures 12 and 13, leadscrew 249 is fitted with a pulley 250, located between the bearing housings 247 and 248. Leadscrew 249 engages with leadscrew nuts 244, 245. Body 246 supports idler pulleys 252, 253. Tooth belt 251, shown partially in figure 13 and also in figure 14, wraps partially around pulley 252, then pulley 250 then pulley

253. Tooth belt 251 drives pulley 250, which in turn rotates leadscrew 249 which moves the jaws 238, 239. Belt 265 is connected to body 246 at a first location 267 and a second location 268. The drive train described allows servo motor 255 to move the jaws 238, 239 together to clamp a brick 225, or apart to unclamp a brick 225. The drive chain described allows servo motor 256 to move the shuttle-B1 along the inside of first boom 12. Thus a brick 225 can be clamped by a shuttle-B1 224 and moved from the first end 269 of first boom 12 to the second end 270 of first boom 12 and then brick 225 (shown in figure 9) can be unclamped. As servo motor 256 moves the shuttle-B1 224 along the boom, servo motor 255 must be synchronised with servo motor 256 to avoid the jaws 238 and 239 from inadvertent movement which could result in the brick being released or over-tightening of the jaws, or the shuttle jaws being run past their intended travel limits.

[0082] It will be seen in the discussion that follows, that the tracks, shuttles and drive assemblies of sticks 15, 17, 18, and 19 follow the same fundamental configuration as that of boom 12.

Winch

[0083] Winches and cables are used to move the telescopic sections of the boom and stick via a system of pulleys. The winch and cable system provides a very light weight means of moving the telescopic sections of the foldable boom. It was found that electric ball screws or hydraulic rams or toothed racks and gears could be used to move the telescopic sections of the boom, but these systems have a higher weight than the cable drive system described. The winch and cable system is detailed below.

[0084] Referring to figures 10 and 41, side plate 219 supports a winch assembly 713. Referring to figure 41, winch 713 winds cables 714, 715 that telescopically move the second boom 14 relative to the first boom 12 (shown in figure 1). Winch assembly 713 has bracket 716 and bracket 717 supported on side plate 219. Bracket 717 supports bearing reducer 718 which is driven by servo motor 719, providing a reduction drive for winch drum 720. Bracket 716 supports a roller bearing 721 that rotateably supports winch drum 720.

[0085] Side plate 219 supports idler pulleys blocks 722, 723, 724, 725. Figure 42 shows a view of the boom 12 with side plate 219 and bottom plate 218 removed for clarity so that the second boom 14 can be seen more clearly. First boom 12 bottom plate 218 supports idler pulley blocks 728, 729, 730, 731. Second boom 14 bottom plate 524 supports idler pulley blocks 726, 727. Cable 714 passes in turn from the

winch drum 720 to pulley block 722 then to pulley block 723, then pulley block 728 then through pulley block 726 then pulley block 731 and then is fastened to the bottom plate 524 of second boom 14. Cable 714 passes in turn from the winch drum 720 to pulley block 724, then to pulley block 725, then to pulley block 729, then through pulley block 727 then through pulley block 730 and then is fastened to the bottom plate 524 of second boom 14. The pulley blocks provide mechanical advantage so that a thin cable can be used. Servo motor 719 rotates the input of bearing reducer 718 which rotates the winch drum 720 which moves cables 714, 715 which slides second boom 14 relative to first boom 12.

[0086] Wear blocks 799 formed from ultra high molecular weight polyethylene (UHMPE) or other suitable material, are secured to the distal end of boom 12 and the near end of boom 14 to provide bearing surfaces for the elements to telescopingly slide. Wear blocks 799 of such material are described throughout this description to provide bearing surfaces for the telescoping parts of both the boom and the stick.

Second Boom

[0087] Referring to figures 17, 18, 19, 20, 21, second boom 14 is of a substantially rectangular or box cross section. Referring to figure 17, second boom 14 is constructed by welding bottom plate 524 to side plates 521, 522, and welding side plates 521, 522 to top plate 523. As with the first boom 12, removable panels (not shown) may be provided in convenient positions along any of the plates 521, 522, 523, 524, to provide access for servicing of internal componentry within second boom 14. Second boom 14 has a first near end 525 and a second distal end 526. Second distal end 526 supports lugs 527, 528. Referring to figure 18, top plate 523 supports channels 529, 530, which form a track to support shuttle-B2 531.

[0088] Shuttle-B2 531 has jaws 532, 533 for the gripping of a brick. Top plate 523 supports bracket assembly 534, which supports idler pulleys 535, 536, 537. Bracket assembly 534 supports servo motors 538, 539. Servo motor 539 drives the jaws 532, 533. Servo motor 538 drives the shuttle-B2 531. Shuttle-B2 531 can move linearly from the first end 525 to the second end 526 of second boom 14. The arrangement is the same as described for the first boom 12 except that the servo motors 538 and 539 are mounted externally on boom 14 to allow the channels 529 and 530 that form the track within second boom 14 to extend from the near end 525, to the distal end 526, so that the shuttle-B2 531 can traverse the entire length of second boom 14.

[0089] Referring to figure 18, side plate 521 supports a boss 562. Boss 562 has a bore 563. Bore 563 supports an end of dog bone link 156 seen in figure 1.

[0090] Refer to figures 4, 20 and 21. An arrangement of energy chains 112 is provided within the boom and stick assembly 141 to carry cables and hoses. Bottom plate 524 supports cable chains 563, 564, 565.

Rotator-B2-S1

[0091] The rotator-B2-S1 548 transfers a brick from the second boom shuttle to the first stick shuttle. It can rotate to align with either the second boom, or the first stick, so that the brick maintains orientation with its longitudinal extent extending with the first stick longitudinal extent, when the brick is transferred from the second boom 12 to the first stick 15. The rotator-B2-S1 548 has movable gripper jaws to grasp the brick. A detailed description follows.

[0092] Referring to figures 20 and 22, bottom plate 524 supports Rotator-B2-S1 548 from supporting bracket 540. Bracket 540 supports bearing reducer 541, which supports servo motor 542. Bearing reducer 542 supports an assembly of arm 543 and base 544. Base 544 supports mount plate 547 which supports servo motor 549. Base 544 also supports linear guides 545, 546. Linear guide 545 supports bearing car 550 which supports jaw 551. Linear guide 546 supports bearing car 552 which supports jaw 553. Mount plate 547 supports bearing 554 (see figure 20), which supports leadscrew 555. Motor 549 has a toothed pulley 556, and leadscrew 555 has a pulley 557, with endless toothed belt 558 wrapped around pulley 556 and pulley 557. Jaw 551 supports nut 556', and jaw 553 supports nut 559 (shown with hidden lines in figure 22). Leadscrew 555 engages with nuts 556', 559. Servo motor 549 thus drives leadscrew 555 to move jaws 551 and 553 together to clamp a brick, or apart to release a brick. Servo motor 542 rotates the input of bearing reducer 541. The output of bearing reducer 541 rotates arm 543 about a horizontal axis 16, which is the same axis as the articulated joint 23 connection of second boom 14 to first stick 15. Thus arranged, rotator 548 can grasp a brick located in shuttle-B2 at the second end 526 of second boom 14 and transfer it to a shuttle-S1 located at the first end 561 of first stick 15.

Joint

[0093] Refer to figure 1. The articulated joint 23 of second boom 14 to first stick 15 about axis 16 is moved by a luffing ram 24 powered by electricity or hydraulics and a first dog bone link 155 and a second dog bone link 156.

[0094] Refer to figure 23 and figure 24. Side plate 568 supports lug 586. Side plate 569 supports lug 587. Side plate 568 supports boss 588. Lugs 586, 587 respectively have concentric bores 589, 590. Bores 589, 590 are on axis 16. Boss 588 has a bore 591. Bore 591 supports a pin not shown that supports an end of dog bone link 156.

First Stick

[0095] Refer to figures 23, 24. First stick 15 has a first near end 561 and a second distal end 566. First stick 15 is of a substantially rectangular or box cross section and welded plate construction, comprising a bottom plate 567, welded to side plates 568, 569, and side plates 568, 569 welded to top plate 570. Side plate 568 supports lugs 574, 575 for connecting an end of luffing ram 24 (shown in figure 1).

Stick Assembly

[0096] The stick assembly has telescopic sticks that can extend and retract. The extension and retraction is servo controlled. Each stick supports channels that in turn support shuttles that move bricks from a first near end to the next stick. The shuttles move back and forth on tracks within their respective sticks. The shuttles are provided with clamps, and can pass a brick along the stick assembly.

Stick Winch and Cables

[0097] The telescopic stick assembly is extended and retracted by a winch that winds cables that wrap around a system of pulleys to move the sticks. The winch is driven by a servo motor and bearing reducer. A detailed description follows.

[0098] Refer to figures 23 and 46. Referring to figure 23, the top plate 570 supports a winch 578. Winch 578 winds cables 579, 580 that telescopically move the second stick 17, third stick 18, fourth stick 19 and fifth stick 20 within and relative to first stick 15 (shown in figure 46).

[0099] Winch 578 is mounted to top plate 570 by bracket 581 and bracket 582. A bearing reducer 583 is provided between servo motor 584' and a winch drum 584. Bracket 581 supports a roller bearing 585 (not visible) that rotateably supports the winch drum 584, at the end thereof away from the bearing reducer 583. Top plate 570 supports pulley blocks 746, 747, 748, 749, 750, 751.

[00100] Figure 46 shows a view of the stick assembly 744. Second stick 17 supports pulley blocks 752, 753. Third stick 18 supports pulley blocks 754, 755. Fourth stick 19

supports pulley blocks 756, 757. Extension cable 580 is wrapped on winch drum 578 and then passes through pulleys 750, 751, then to second stick 17 pulley block 752, then to pulley block 753, then to third stick 18 pulley block 754, then to pulley block 755, then to fourth stick 19 pulley block 756, then to pulley block 757, then to a termination 758 on fifth stick 20. Tension on cable 580 forces the stick assembly 744 to extend.

[00101] Referring to figure 47, retraction cable 579 is wrapped on winch drum 578 and then passes through pulley blocks 746, 747, 748 and 749 and then runs internally inside stick assembly 744 to termination 759 on fifth stick 20. Tension of cable 579 forces the stick assembly 744 to retract.

[00102] Figure 48 shows a view of stick assembly 744. Cables 759, 760 and 761 act to keep the extension of each stick, relative to its neighbours, similar. Second stick 17 supports pulley block 762. First stick 15 supports a termination 765 of first end 771 of cable 759. Cable 759 passes through pulley block 762 and third stick 18 supports a termination 766 of second end 772 of cable 759. Third stick 18 supports a pulley block 763. Second stick 17 supports a termination 767 of first end 773 of cable 760. Cable 760 passes through pulley block 763. Fourth stick 19 supports a termination 768 of second end 774 of cable 760. Fourth stick 19 supports pulley block 764. Third stick 18 supports a termination 769 of first end 775 of cable 761. Cable 761 passes through pulley block 764. Fifth stick 20 supports a termination 770 of second end 776 of cable 761.

First Stick

[00103] Referring to figures 23 and 24, the top plate 570 supports a track in the form of longitudinally extending channels 571, 572, inside the stick 15. Channels 571, 572 run from the first near end 561 of first stick 15, nearly to the second distal end 566, save room for the drive assembly 592 at the end of the track, inside the first stick 15. Channels 571, 572 slideably support shuttle-S1 573. Shuttle-S1 573 has jaws 576, 577 provided to clamp a brick.

[00104] Top plate 570 supports drive assembly 592 inside first stick 15, in the same manner as that of the first boom 12. Top plate 570 supports bracket 593, which supports idler pulleys 594, 595, 596, 597. Servo motors not shown on drive assembly 592 move the shuttle-S1 573 along the top of and inside first stick 15 and can open and close jaws 576, 577 to grip or release a brick. Thus shuttle 573 can grasp a brick at first near end 561 of first stick 15 and move it to or toward second distal end 566 of

first stick 15, then unclamp the brick not shown. The mechanism for this functions in the same manner as that of the first boom 12 and its shuttle. The jaws 576 and 577 each include a deviation 576' and 577' which aligns with the bracket assembly 534 of second boom 14, to provide clearance to receive bracket assembly 534 at the distal end of second boom 14, when the shuttle-S1 573 moves in to take a brick from rotator-B2-S1 548 when second boom 14 and first stick 15 are aligned in line, as shown in figure 57C.

Second Stick

[00105] Refer to figures 25, 26, 27. Referring to figure 25, second stick 17 has a first near end 598 and a second distal end 599. Second stick 17 is hollow and internally supports a shuttle that moves bricks from the first near end 598 to or toward the second distal end 599.

[00106] Second stick 17 is preferably constructed from carbon fibre sandwich panels for low weight. Alternatively, second stick 17 may be welded with metal plates. Second stick 17 is of a substantially rectangular or box cross section. Second stick 17 is constructed by welding or bonding bottom plate 600 to side plates 601, 602. Side plates 601, 602 are welded or bonded to top plate 603. Bottom plate 600 supports a track formed by longitudinally extending channels 604, 605. Channels 604, 605 support shuttle-S2 606 for movement therealong. Shuttle-S2 606 has jaws 607 and 608 to grasp a brick. Referring to figure 26, bottom plate 600 supports bracket 609 which supports idler pulleys 610, 611, 612, 613. Referring to figure 27, bottom plate 600 supports drive assembly 614 located at the distal end 599 of second stick 17, which moves belts 615 and 616, in order to move shuttle-S2 606 (shown in figure 26) and open and close jaws 607, 608, in the same manner as that of the first boom 12 and its shuttle. Thus shuttle-S2 can grasp a brick located at the first near end 598 of second stick 17 and move the brick to or toward the second distal end 599 of second stick 17 and unclamp the brick. The second stick 17 has a void in the top plate 603 at the near end 598 (shown in figure 26), which is opposite the track formed by channels 604 and 605. This allows the shuttle-S1 573 of the first stick 15 to line up above the shuttle-S2 606 to enable the clamps thereof to transfer a brick from shuttle-S1 573 to shuttle-S2 606.

Third Stick

[00107] Refer to figures 28, 29 and 30. Referring to figure 28, third stick 18 has a first near end 618 and a second distal end 619. Third stick 18 is preferably constructed

from carbon fibre sandwich panels for low weight. Alternatively, third stick 18 may be constructed with welded metal plates. Third stick 18 is of a substantially rectangular or box cross section. Third stick 18 is constructed by welding or bonding bottom plate 620 to side plates 621, 622. Side plates 621, 622 are welded or bonded to top plate 623. Referring to figure 29, top plate 623 supports a track formed by longitudinally extending channels 624 and 625 which extend from the first near end 618 to the drive assembly 634 located at the second distal end 619, shown on figure 30. Channels 624, 625 support shuttle-S3 626 for movement along third stick 18 from first near end 618 to or toward second distal end 619. Shuttle-S3 626 has jaws 627 and 628, to clamp a brick. Top plate 623 supports bracket 629. Bracket 629 supports idler pulleys 630, 631, 632, 633. Referring to figure 30, top plate 623 supports drive assembly 634 at the second distal end 619, which moves belts 635 and 636. Drive assembly 634 can move shuttle-S3 626 and open and close jaws 627, 628. Thus shuttle-S3 can grasp a brick located at the first end 618 of third stick 18 and move said brick to or toward the second end 619 of second stick 18 and unclamp the brick, in the same manner as that of the first boom 12 and its shuttle. The third stick 18 has a void in the bottom plate 620 at the near end 618, which is opposite the track formed by channels 624 and 625. This allows the shuttle-S2 606 of the second stick 17 to line up above the shuttle-S3 626 to enable the clamps thereof to transfer a brick from shuttle-S2 606 to shuttle-S3 626.

Fourth Stick

[00108] Refer to figures 31, 32, 33. Referring to figure 31, fourth stick 19 has a first near end 637 and a second distal end 638. Fourth stick 19 is preferably constructed from carbon fibre sandwich panels for low weight. Alternatively, fourth stick 19 may be constructed from welded metal plates. Fourth stick 19 is of a substantially rectangular or box cross section. Fourth stick 19 is constructed by welding or bonding bottom plate 640 to side plates 641, 642. Side plates 641, 642 are welded or bonded to top plate 643. Bottom plate 640 supports a track formed by longitudinally extending channels 644, 645. Channels 644, 645 extend from the near end 637 to drive assembly 654 located at the distal end, and support shuttle-S4 646 (shown on figure 32) for linear movement therealong. Referring to figure 32, shuttle-S4 646 has jaws 647 and 648 to grasp a brick. Bottom plate 640 supports bracket 649 at the near end 637 which 649 supports idler pulleys 650, 651, 652, 653. Referring to figure 33, bottom plate 640 supports drive assembly 654 at the distal end 638, inside fourth the stick 19. Drive assembly 654 moves belts 655 and 656 in order to move shuttle-S4 646 along fourth stick and open and close jaws 647, 648, in the same manner as that of the first boom

12 and its shuttle. Thus shuttle-S4 646 can grasp a brick located at the first end 637 of fourth stick 19 and move it to or toward the second end 638 of fourth stick 19 and unclamp the brick. Referring to figure 32, the fourth stick 19 has a void in the top plate 643 at the near end 637, which is opposite the track formed by channels 644 and 645. This allows the shuttle-S3 626 of the third stick 18 to line up above the shuttle-S4 646 to enable the clamps thereof to transfer a brick from shuttle-S3 626 to shuttle-S4 646.

Fifth Stick

[00109] Refer to figures 34, 35, 36 and 37. Referring to figure 34, fifth stick 20 has a first near end 657 and a second distal end 658. Fifth stick 20 is preferably constructed from carbon fibre sandwich panels for low weight. Alternatively, fifth stick 20 may be constructed from welded metal plates. Fifth stick 20 is of a substantially rectangular or box cross section. Fifth stick 20 is constructed by welding or bonding bottom plate 660 to side plates 661, 662. Side plates 661, 662 are welded or bonded to top plate 663. Top plate 663 supports a track formed by longitudinally extending channels 664, 665, which extend from the near end 657 to the drive assembly 663, along the inside of the fifth stick 20. Referring to figure 35, channels 664, 665 support shuttle-S5 666 for linear movement therealong. Shuttle-S5 666 has jaws 667, 668 provided to grip a brick. Top plate 663 supports bracket 669 at the near end 657 which supports idler pulleys 670, 671, 672, 673. Referring to figure 36, top plate 663 supports drive assembly 674 at the distal end 658. Drive assembly 674 moves belts 675 and 676 in order to move shuttle-S5 666 and open and close jaws 667, 668 (shown in figure 35). Drive assembly 674 moves belts 675 and 676 in order to move shuttle-S5 666 along fifth stick and open and close jaws 647, 648, in the same manner as that of the first boom 12 and its shuttle. Shuttle-S5 666 can grasp a brick presented by shuttle-S4 646 located through a void located at the near end 657 of the bottom plate 660. Shuttle-S5 666 then moves the brick along the inside of fifth stick 20 to the second distal end 658 of fifth stick 20, where it will be unclamped.

[00110] The panels or plates making up each of the first stick 15, second stick 17, third stick 18, fourth stick 19 and fifth stick 20 may be provided with removable panel portions (not shown) to provide access for servicing of internal componentry within each stick.

Boom Cable Chains

[00111] Cable chains are used to route power and signals to and from the servo motors. The arrangement of the cable chains provides a compact over all cross section of the folding boom.

[00112] Referring to figure 43, bottom plate 218 of first boom 12, supports a first end 735 of cable chain 112. Cable chain 112 is also visible in figures 11, 18, 19. The top plate 22 of second boom 14, supports a second end 736 of cable chain 112.

[00113] First near end 637 of fourth stick 19 supports a first end 737 of cable duct 733. Second end 738 of cable duct 733 supports a first end 739 of cable chain 734. The bottom plate 660 of fifth stick 20, supports the second end 740 of cable chain 734. Cable chain 734 and cable duct 733 are also visible in figure 34.

[00114] Referring to figure 44, the bottom plate 524 of second boom 14, supports a first end 741 of cable chain 563. The top plate 623 of third stick 18 supports a second end 742 of cable chain 563. Cable chain 563 is also visible in figures 17, 18, 19, 20.

[00115] Referring to figure 45, the bottom plate 524 of second boom 14 supports a first end 743 of cable chain 564. The top plate 643 of fourth stick 19 supports a second end 744' of cable chain 564. Cable chain 564 is also visible in figures 17, 18, 19, 20.

[00116] Referring to figure 1, cables (not shown) are routed from an electrical cabinet through the frame 3, through the centre of slew ring 11, up through the inside of tower 10 and into first boom 12, then into cable chain 112 (shown in figure 43), then into second boom 14. Referring to figure 43, cables (not shown) are routed from second boom 14, to first stick 15, and to cable chain 565 and then into second stick 17, and as shown in figure 44 also into cable chain 563 and then into third stick 18, and as shown in figure 45 also into cable chain 564 and then into fourth stick 19.

[00117] Referring to figure 43, (cables not shown) are routed from fourth stick 19, through cable duct 733 into cable chain 734 then into fifth stick 20. From fifth stick 20, cables not shown are routed to the brick laying and adhesive applying head 32.

Flipper

[00118] Refer to figures 37, 38, 39. Referring to figure 37, a pivotable clamp in the form of a flipper assembly 687 has jaws 690 and 693 to grip a brick and can then translate and rotate the brick to move it past an adhesive application nozzle 121, 122, 123, 124 and 125 and then present the brick for transfer to the laying arm. The flipper assembly 687 is located at the distal end 658 of the fifth stick 20.

[00119] Figures 58A to 58Q show a sequence for a brick as it passes from the fifth stick to its laid position.

[00120] During the laying of bricks, the brick laying and adhesive applying head 32 is held at a constant tilt relative to the ground. The pose of the foldable boom is varied to position the brick laying and adhesive applying head 32 appropriately for the brick laying and adhesive applying head 32 to lay bricks in the required position. The angle of the stick assembly, varies according to the required pose of the foldable boom. The flipper assembly 687 is used to receive a brick from the stick assembly (Figure 58A) and move the brick to a position suitable for an adhesive applicator 777 in the brick laying and adhesive applying head 32 to apply glue to said brick (Figures 58D - 58G), and then for the brick laying gripper 44 to lay the brick (Figure 58Q). Referring to figure 38, the flipper assembly 687 rotates about axis 33. The flipper assembly 687 has a gripper with jaws 690 and 693 that can slide toward or away from the axis of rotation 33 (which is the same horizontal axis of the mount of the brick laying and adhesive applying head 32 to the end of fifth stick 20). The gripper can extend into the fifth stick 20 to grasp a brick (Figure 58B). The gripper then retracts to a position near the axis of rotation 33 (Figure 58C) so that the brick is clear of the fifth stick 20. The brick is then rotated for the application of adhesive (Figure 58D). The adhesive application nozzles are extended out over the brick (Figures 58E, 58F). The adhesive nozzles direct adhesive downwards so that gravity assists in applying the adhesive to the brick. The adhesive application nozzles are retracted whilst directing adhesive onto the brick (Figure 58G). The flipper 687 then rotates (Figure 58H) to orient the brick vertically (Figure 58J), so that adhesive application nozzles can apply adhesive to the end of the brick. The flipper then rotates (Figure 58K) to invert the brick (Figure 58L) so that the adhesive is on the bottom of the brick. The flipper 687 then extends the gripper out (Figure 58M), to present the brick in a position where the brick laying gripper 44 can then grasp the brick (Figure 58N). The flipper gripper then releases the brick and the flipper gripper then translates in a reverse direction whilst the flipper rotates in a reverse rotation (Figure 58P, 58Q) so that the gripper is returned to its starting position (Figure 58A).

[00121] A detailed description of the flipper assembly follows.

[00122] Refer to figure 37. Fifth stick 20 supports the flipper assembly 687 about the same horizontal axis 33 as the brick laying and adhesive applying head 32 is attached to the distal end of the fifth stick 20 (see figure 58A).

[00123] Refer to figures 36, 37, 38 and 39. Referring to figure 37 the fifth stick 20 supports a bearing reducer 677 and a servo motor 678. Bearing reducer 677 supports an arm 679 of the flipper assembly 687 on its output, and a servo motor 678 rotates the input of bearing reducer 677. This rotates arm 679 and hence the flipper assembly 687 about axis 33. Referring to figure 38, the arm 679 supports a linear guide 680 which slideably supports a bearing car 681 for movement between a first end 707 and a second end 708 of the arm 679. A base plate 682 mounts to the bearing car 681, perpendicularly to the travel extent thereof. Referring to figure 39, a servo motor 684 for movement of the base plate 682 is mounted via a spacer 683 to the arm 679. Referring to figure 38, a servo motor 686 for movement of jaws 690 and 693 is mounted on motor mount plate 685 which is supported on base plate 682. Base plate 682 supports linear guides 688, 689 which slideably support bearing cars 691 and 692 respectively. Bearing car 691 supports jaw 690, and bearing car 692 supports jaw 693. Servo motor 686 drives pulley 694 which drives pulley 696 connected to leadscrew 695 via endless toothed belt 697. Referring to figure 39, base plate 682 supports a bearing 700 which rotateably supports the leadscrew 695. Referring to figure 38, jaw 690 supports a nut 698, and jaw 693 supports a nut 699, which nuts 698 and 699 are engaged with the leadscrew 695. Thus servo motor 685 drives the jaws 690 and 693 to clamp and unclamp a brick.

[00124] Referring to figure 38, the arm 679 supports a bracket 701 with an idler pulley 702 near end 708. Servo motor 684 (shown in figure 39) drives a pulley 703, which drives pulley 702 via endless belt 704. The base plate 682 has a clamp plate 705 (shown in figure 39) which clamps belt 704. Thus the servo motor 684 linearly moves base plate 682 along linear guide 680.

[00125] Refer to figure 37. Servo motor 678 can rotate arm 679 so that linear guide 680 is aligned parallel with the channels 664, 665 in fifth stick 20.

[00126] Jaws 690 and 693 can be moved by servo motor 684 towards the second distal end 658 of fifth stick 20 to pick up a brick (see figure 58B) that is being held by jaws 667, 668 of shuttle-S5 666. Servo motor 686 can then close jaws 690 and 693 to grasp the brick. Servo motor 684 can then move jaws 690, 693, holding the brick towards first end 707 of arm 679 (see figure 58C). Servo motor 678 can then rotate arm 679 so that the top surface of said brick is presented flat, ready for adhesive application by the adhesive application system 150 (see figures 58D to G).

[00127] Optionally, servo motor 684 can then rotate arm 679 through 90 degrees so that the end of said brick is presented flat, ready for adhesive application by the

adhesive application system 150 (see figures 58H and J). It should be noted that in some structures, such as for walls that will be rendered, it is not necessary to apply adhesive to the vertical (or "perp") joints of the bricks. Optionally, servo motor 684 can then rotate arm 679 through 180 degrees so that the opposite end of said brick is presented flat, ready for adhesive application by the adhesive application system 150, thereby applying adhesive to the bottom and both ends of said brick.

[00128] Servo motor 684 can then rotate arm 679 through 180 degrees (or 90 or 270 degrees, depending on which faces of the brick had adhesive applied to them), so that said brick is inverted, ready to be picked up by the laying arm gripper 44 (see figures 58K to Q). In this way the glue is applied to the bottom of said brick that will be laid by the laying arm 40.

[00129] Figure 53 shows a side view of the brick laying and adhesive applying head 32 and fifth stick 20. Figure 53 shows the sequence of the brick 797 from a first position 791, to a second position 792, to a third position 793 to a fourth position 794 to a fifth position 795 to a sixth position 796. In first position 791, brick 797 is gripped by shuttle-S5 666 (not shown in figure 53). The flipper jaws 690 and 693 are moved to grasp the brick 797 and then shuttle-S5 666 releases the brick 797. The brick 797 is then translated to second position 792, then rotated to third position 793. Adhesive is then applied to the brick 797. Brick 797 is then optionally rotated to vertical position 794. Brick 797 is then rotated to a fifth position 795 and then translated to a sixth position 796.

Adhesive

[00130] Referring to figure 1, the frame 3 supports an adhesive container and an adhesive pump. The adhesive pump supplies pressurised adhesive to fluid conveying apparatus in the form of a hose which runs out along the boom and through the flexible energy chains 112 (shown in figure 43), 564 (shown in figure 45) and 740 (shown in figure 43) provided in the telescopic boom and telescopic sticks, to the brick laying and adhesive applying head 32. Adhesives can be one pack or two pack, and should have some flexibility when set in order to avoid fracturing due to uneven expansion and contraction in the built structure. Suitable adhesives are single pack moisture curing polyurethane such as Sika "Techgrip", Hunstman "Suprasec 7373" or Fortis AD5105S, single pack foaming polyurethane such as Soudal "Souda Bond Foam" or Weinerberger "Dryfix", two part polyurethane such as that made by Huntsman, MS Polymer (Modified Silane Polymer) such as HB Fuller "Toolbox", two part epoxy such as Latipoxy310 and methacrylate adhesive such as "Plexus". It would be possible but less desirable (due to

strength, flexibility and "pot life" and clean up reasons) to utilise water based adhesives such as latex, acrylic or cement based adhesives similar to various commercially available tile glue or Austral Bricks "Thin Bed Mortar".

[00131] Refer to figures 5 and 6. The adhesive applicator 777 has an adhesive head fitted with nozzles 121, 122, 123, 124 and 125, shown schematically in figure 6. The adhesive flow is controlled by electrically operable valves 118 and 119, located in a manifold head 117, close to the nozzles 121, 122, 123, 124 and 125, which are also supported on the manifold head 117. Space within the laying head is very restricted. The nozzles provided in two groups comprising a central group of nozzles 121, 122 and 123 supplied by valve 118, and a peripheral group of two outer nozzles 124 and 125 supplied by valve 119. The manifold head 117 is supported on a mechanism that can project the nozzles out to reach the length of a brick, and retract the nozzles to provide clearance so that the brick can be rotated and also by retracting the nozzles clearance is provided so that the laying head can be folded against a retracted stick assembly for compact transport. To achieve the extension and retraction, the nozzles are supported on a chain that can only bend one way and the chain is extended or retracted by a sprocket driven by a servo motor. A detailed description follows.

[00132] Refer to figures 5, 6, 40 and 49. Referring to figure 40, the brick laying and adhesive applying head 32 supports an adhesive applicator assembly 777. Referring to figure 49, the adhesive applicator assembly 777 has a curved guide 113 attached to the brick laying and adhesive applying head 32. The curved guide 113 supports a tongue member in the form of a sliding chain 114 that can only bend one way. The sliding chain 114 is moved by a servo powered sprocket 115. The brick laying and adhesive applying head 32 supports a straight guide 784 into which the sliding chain 114 may be retracted. The distal end 116 of the sliding chain 114 supports a manifold 117 that supports two valves 118, 119. Each valve 118, 119 is connected to the pressurised adhesive supply 120 provided by the adhesive pump 111 mounted to the frame 3 (shown in figure 5). The first valve 118 is connected to three central glue nozzles 121, 122, 123, and the second valve 119 is connected to two outer glue nozzles 124, 125 (shown schematically in figure 13). The inner nozzles 121, 122, 123 are provided to allow glue to be applied to the top face of a narrow or internal brick, while the outer nozzles 124, 125 allow glue to be applied to the outer edges of the top face of a wide or external brick 126. The valves 118, 119 may be operated individually or together to supply glue to the inner nozzles 121, 122, 123, the outer nozzles 124, 125 or all nozzles 121, 122, 123, 124 and 125. The adhesive is applied in a direction extending

downwardly from the valves on the manifold, the manifold being disposed on the sliding chain 114 which is disposed horizontally.

[00133] Refer to figures 50 and 51. Referring to figure 50, the sliding chain 114 has a plurality of body portions in the form of hollow links 778 and a plurality of chain links in the form of joiner links 779. Joiner links 779 are standard items used to join power transmission chain, such as BS roller chain 16-B1 or ANSI roller chain 80-1. Referring to figure 51, hollow link 778 is provided with lugs 780, 781 to engage the pins 782 of joiner links 779 shown in figure 50. Hollow link 778 is provided with a longitudinally extending hole 783 for the passage of cables (not shown) and the pressurised adhesive 120 (see figure 13). The hollow links have ends that contact each other to prevent over extension of the sliding chain, allowing the sliding chain to be extended outward from the tip of the curved guide and retain a straight configuration, being bendable upward only, about the axes provided by the connection of the hollow links with the joiner links.

[00134] Referring to figure 52, the straight guide 784 is fitted with a lid 788. In figure 49 curved guide 113 is shown with the lid 787 removed for clarity. Straight guide 784 is shown without the lid 788 for clarity.

[00135] Referring to figure 50, consider the example of first hollow link 778, joiner link 779 and second hollow link 784'. It can be seen that second hollow link 784' can pivot upwards relative to first hollow link 778, but second hollow link 784' cannot pivot downwards relative to first hollow link 778. By extension of the logic to the plurality of hollow links 778 and joiner links 779, the sliding chain 114 can only curve upwards and not curve downwards.

[00136] Preferably the hollow links 778 are manufactured from a material with a low coefficient of friction such as acetal copolymer or UHMWPE (Ultra High Molecular Weight Polyethylene) plastic. The curved guide 113 and straight guide 784 may be manufactured from a material with a low coefficient of friction such as acetal plastic.

[00137] Figure 52 shows a top view of straight guide 784. The straight guide 784 is provided with grooves 785, 786 so that joiner links 779 do not touch straight guide 784. Straight guide 784 may then be constructed from a material such as aluminium alloy which is more robust than acetal plastic.

[00138] Referring to figure 49, the curved guide 113 is also provided with grooves 789, 790 so that joiner links 779 do not touch curved guide 113. Curved guide 113 may

then also be constructed from a material such as aluminium alloy which is more robust than acetal plastic.

[00139] The tongue in sheath arrangement of the adhesive applicator allows a single axis of servo motion control to move a nozzle for application of adhesive whilst maintaining a vertical nozzle orientation and also to retract the nozzle to allow for movement of the brick to the next step of the process. The laying head space is quite limited, so to achieve the application and retraction with more conventional linear movement mechanisms or articulating arm robots would require the use of two or more servo axes of motion or the addition of linkages and cam mechanisms.

Brick Laying and Adhesive Applying Head

[00140] Refer to figure 40. The brick laying and adhesive applying head 32 supports a brick laying head in the form of a spherical geometry robot 36 and the adhesive applicator assembly 777 along with a vision system and tracking system. After application of adhesive as described above, the brick laying and adhesive applying head 32 takes a brick from the jaws 690 and 693 of the flipper assembly 687 and moves it to a position where it is laid. The laying head also compensates for movement and deflection of the boom, so that the brick is laid in the correct position.

[00141] Refer to figures 1, 5 and 40. Referring to figure 40, the articulated brick laying and adhesive applying head 32 has a body 801 with arms 803 and 805 forming a clevis which extends obliquely downward from the body 801. The arms 803 and 805 have apertures 807 and 809 to receive pins to pivotally mount the head 32 and the flipper assembly 687 about second horizontal axis 33 at the distal end 658 of the fifth telescopic stick 20 (see figure 1). Referring to figure 1, the brick laying and adhesive applying head 32 articulates about horizontal axis 33 substantially parallel to the articulation axis 16 of the first stick 15 and the articulation axis 13 of the first boom 12. The pose of the brick laying and adhesive applying head 32 is controlled by movement of a ram 35.

[00142] Referring to figure 40, the articulated brick laying and adhesive applying head 32 supports a brick laying head comprising a spherical geometry robot 36. The spherical geometry robot 36 has a linearly extendable arm 40 with a brick laying clamp in the form of a gripper 44 fitted at the lower end thereof. Referring to figure 1, the spherical geometry robot 36 has the following arrangement of joints: arm mount-roll angle 37, arm mount-pitch angle 38, arm sliding (arm length or linear extension) 39, wrist pitch angle 41, wrist roll angle 42, gripper yaw angle 43 and with gripper 44 fitted

to rotate about yaw axis 45. This configuration provides pole free motion within the working envelope.

[00143] Referring to figure 40 and 61, to achieve the arm mount-roll angle 37 adjustment, the body 801 supports a servo motor 810 with a belt driving a bearing reducer 812 connected to the base 811 of a clevis 813, the base being rotatable relative to the body 801 about a horizontal axis which runs normal to the clevis 813 axis. To achieve the arm mount-pitch angle 38 adjustment, the clevis 813 supports about its axis 814 a servo motor 816 attached to the body 801 driving via a belt a bearing reducer 818 connected to a base 815 for the arm 40.

[00144] The arm 40 has linear guides 820 which co-operate with bearing cars 822 (see figure 62) on the base 815 to guide linear extension of the arm relative to the mount, to allow the arm 40 to move in a direction (typically straight up and down, but this depends on the pose) normal to the axis 814 of the clevis 813 to provide sliding movement of the arm 40. This linear extension of the arm is controlled by a servo motor 823 attached to the base 815 with reduction drive pulleys connected by a toothed belt 825 driving a pinion 827 engaging a rack 829 located extending along the arm 40.

[00145] The brick laying clamp/gripper 44 mounts for controlled rotation by a servo motor 830 driving a bearing reducer 831 about an axis normal and perpendicular to the plane of its jaws 833, 835 and bearing reducer on a clevis 817 to provide the gripper yaw angle 43 adjustment; a universal joint formed by mechanism 819 comprising servo motor 837 and bearing reducer 839 connected by toothed belt 841 and pulleys provides wrist pitch angle 41 adjustment; and mechanism 821 comprising servo motor 843 and bearing reducer 845 driven by toothed belt 847 and pulleys provides wrist roll angle 42 adjustment (shown in figure 1). Details of these servo motors and drives can be seen in figure 85.

[00146] The brick laying and adhesive applying head 32 supports a hook 151 that can be used to lift items such as windows, doors, lintels and other items not shown.

[00147] Refer to figure 5 and figure 6. The brick laying and adhesive applying head 32 supports machine vision cameras 127, 128 mounted to view both sides of the brick 126 shown schematically in figure 13.

[00148] The jaws 835, 833 of the laying head gripper 44 are independently movable by independent lead screws 849, 851, engaged with nuts 853, 855 connected with the

jaws 835, 833, and moveable by servo motors 857, 859, via drive belts 861, 863 respectively. This allows the offset gripping of a brick. The arrangements for moving the jaws 835, 833 use lead screws 849, 851 and co-operating nuts 853, 855, driven by separate servo motors 857, 859, respectively, similar to that as described for other grippers utilised elsewhere in the embodiment, apart from the drives for the jaws being separate in order to allow independent movement of the jaws.

[00149] As can be seen in figure 40, when considered with figure 49, the straight guide 784 of the adhesive applicator assembly 777, into which the sliding chain 114 may be retracted, is mounted in the body 801 of the brick laying and adhesive applying head 32, behind the servo motor with bearing reducer that connects to clevis 813. The curved guide 113 of the adhesive applicator assembly 777 descends/depends downwardly obliquely, substantially following the extent of the arms 803 and 805 for a short distance, before curving toward horizontal so that the sliding chain is presented extending substantially level, subject to the alignment of the brick laying and adhesive applying head 32 as controlled by the ram 35, and presented above where the flipper assembly 687 holds the brick. With this arrangement, the adhesive applicator assembly 777 is kept clear of positions through which arm 40 and gripper 44 of the spherical geometry robot 36 could be required to move.

Tracker and Slab Scan

[00150] Referring to figures 1, 5, 40, the top of the brick laying and adhesive applying head 32 supports a tracker component 130. The tracker component 130 may be a Leica T-Mac or an API STS (Smart Track Sensor). Alternately tracker component 130 may be a single SMR (Spherical Mount Reflector) or corner cube reflector, or two or three SMRs or corner cube reflectors or a Nikon iGPS or any other suitable tracking device. Preferably the tracker component 130 provides real time 6 degrees of freedom position and orientation data at a rate of preferably greater than 10kHz, or preferably 1000Hz to 10kHz, or preferably at a rate of 500Hz to 1000Hz or preferably a rate of 300Hz to 500Hz or 100Hz to 300Hz or 50Hz to 100Hz or 10Hz to 50Hz. The laying arm 40 and or the gripper 44 of the laying arm 40 may support a second or third tracker component 131, 132 of the same or different type to the first tracker component 130.

[00151] Referring to figure 3, a tracker component 133 or components, 133, 134, 135 are set up on the ground adjacent to the concrete slab 136 or on a nearby structure. The tracker component 130 on the laying head references its position relative to the tracker component 133 or components 133, 134, 135 set up on the ground or structure.

[00152] Referring to figure 5, the brick laying and adhesive applying head 32 supports a camera 137 that views the ground, slab 136 or structure or objects below it. The brick laying and adhesive applying head 32 is provided with laser or light projectors 138 that project dots or lines 139 onto the ground, footings, slab 136 or objects below it. Machine vision is used to determine the 3D shape of the ground, footings, slab 136 or objects below the laying head. Alternatively, the brick laying and adhesive applying head 32 is fitted with a laser scanner 140. After positioning the truck and unfolding the boom, the brick laying and adhesive applying head 32 is moved around by moving the boom and stick assembly 141 so that the brick laying and adhesive applying head 32 is optionally moved around the edge of the slab 136 and optionally above all positions that will be built upon. The machine vision system 143 or scanner 140 scans the slab 136 and the areas to be built on to firstly align the slab 136, machine 2 and working coordinate systems to their correct locations and secondly to quality check the slab 136 and check its flatness and level. If the slab 136 is not flat or level within tolerance the first course of bricks or selected bricks not shown can be individually machined, prior to being transported to the tower 10 and boom and stick assembly 141, to correct the out-of-level, flatness or height. Optionally a brick may have a groove or notch or pocket machined in it to avoid a bump or defect or object (such as a pipe projecting through the slab) on the slab 136.

[00153] As the brick laying and adhesive applying head 32 lays a brick 144, the machine vision 143 or laser scanner 140 is used to measure the laid brick 144 so that the height of the laid brick 144 is stored and later used to adjust the laying height of the dependant bricks that are laid on top of it on the next course. If the height is over tolerance, the dependant bricks above it can be machined to a reduced thickness by the router 47.

[00154] The concrete slab 136 may alternatively be a slab of earth, rock, wood, plastic or other material or a steel deck or footings. The slab 136 may be on the ground or suspended.

Harsh Environment

[00155] In an adaptation with radiation protection, of the brick laying and adhesive applying head, incorporated on a telescoping boom, foldable boom or articulated telescoping boom, , the brick laying and adhesive applying head could be used for erecting containment structures in nuclear disaster zones.

[00156] In a further adaptation of the brick laying and adhesive applying head, it may be adapted to work in a low pressure atmosphere or in a vacuum and in the presence of ionising radiation. In this format with an integral automated brick or block making unit, the brick laying and adhesive applying heads could be used for building structures on the moon or Mars or in other extra-terrestrial locations.

Advantages of the Invention

[00157] In the embodiment with the adhesive applicator incorporated with a brick laying head, the adhesive applicator allows for a compact configuration of the brick laying and adhesive applying head. The adhesive applicator is actuated along a single axis of motion, which provides reduced complexity compared with an alternative arrangement that could require movement along two or more axes. The configuration of the adhesive applicator, results in the adhesive applicator being retractable so as to keep well clear of the brick laying head, so as to not impede its operation. When provided on a boom incorporated in a vehicle, the invention provides an improved automated brick laying machine that is compact and mobile and able to drive on public roads. The arrangement and configuration of the brick laying and adhesive applying head with attached boom allows the machine to have a very large working envelope whilst also being compact for road travel.

[00158] It should be appreciated that the scope of the invention is not limited to the particular embodiment described herein, and the skilled addressee will understand that changes can be made without departing from the spirit and scope of the invention.

The Claims Defining the Invention are as Follows

1. An adhesive applicator tool for machine application of adhesive, said adhesive applicator tool comprising an adhesive applicator head having at least one nozzle fed with adhesive under pressure for selective application to a surface, said adhesive applicator head being supported on a distal end of a tongue member, said tongue member being housed in a sheath for linear movement to extend said adhesive applicator head across said surface for application of adhesive, and retract said tongue within said sheath to withdraw said adhesive applicator head away from said surface, said tongue being rigid when extended obliquely or horizontally and freely deflectable in only one dimension upwardly, about horizontal axes.
2. An adhesive applicator tool as claimed in claim 1 wherein said sheath has a tip which in use is located aligned horizontally, so that said tongue extends horizontally from the tip of said sheath.
3. An adhesive applicator tool as claimed in claim 1 or 2 wherein said sheath curves upwardly from said tip, with the tongue being freely deflectable about horizontal axes allowing the tongue to move within said sheath.
4. An adhesive applicator tool as claimed in any one of the preceding claims wherein said tongue is configured as a chain-link-type actuator, said chain-link-type actuator being linearly moveable by a driven sprocket to selectively extend and retract said tongue from said tip of said sheath.
5. An adhesive applicator tool as claimed in claim 4 wherein said chain link type actuator comprises a chain having body portions attached to one side, said body portions having ends that contact ends of adjacent body portions preventing said chain folding about said horizontal axes in one direction away from a horizontal alignment of said chain.
6. An adhesive applicator tool as claimed in claim 4 wherein said tongue comprises a plurality of body portions, each body portion having on a top surface at least one pivot mount with a transverse aperture extending horizontally therethrough to provide a connection point for a chain link to an adjacent said pivot mount of an adjacent said body portion, each said body portion having opposed ends that contact ends of adjacent body portions, said tongue being foldable in one direction only about said transverse apertures, the opposed ends of adjacent body portions coming into contact preventing said tongue folding about said connection points in the opposite direction.

7. An adhesive applicator tool as claimed in claim 5 or 6 wherein each said body portion has a channel extending longitudinally therethrough, for routing services such as wiring and tubing for the transport of adhesive to said adhesive applicator. The channel may be an inverted u-channel with the pivot mounts being located on top of the web.
8. An adhesive applicator tool as claimed in claim 7 wherein the channel is closed, to fully enclose said services extending longitudinally through said tongue.
9. An adhesive applicator tool as claimed in any one of claims 6 to 8 wherein there are two said pivot mounts located on top of each said body portion, one said pivot mount located near each opposed end of said body portion.
10. An adhesive applicator tool as claimed in claim 9 wherein on each body portion, said pivot mounts are spaced apart from each other by the same longitudinal distance as the sum of the longitudinal distances from each to the closest end of said body portion, to form teeth of a cog on top of the assembled tongue, to be engaged by a driven sprocket to selectively extend and retract said tongue from said tip of said sheath.
11. A brick laying and adhesive applying head for a brick laying machine, said brick laying and adhesive applying head having a clevis with a horizontal axis for pivot mounting for controlled rotation to the remote end of a boom, said brick laying and adhesive applying head including a pivotable clamp to receive and clamp a brick presented at the remote end of said boom, said pivotable clamp being pivotally mounted about said horizontal axis; said brick laying and adhesive applying head supporting an adhesive applicator tool aligned to extend said adhesive applicator across a brick presented by said pivotable clamp; said brick laying and adhesive applying head having a brick laying head mounted thereto by a mount located in a position away from said clevis, said brick laying head having a brick laying clamp moveable between a position to receive and clamp a brick held by said pivotable clamp, to a position in which said brick is released and laid.
12. A brick laying and adhesive applying head as claimed in claim 11 wherein the brick laying head includes a spherical geometry robot.
13. A brick laying and adhesive applying head as claimed in claim 11 wherein said brick laying head includes a linearly extendable arm depending downward, attached about a mount roll-axis to said mount, said mount roll-axis allowing controlled roll

motion in said arm relative to said mount, said brick laying clamp being mounted for controlled motion to the end of said linearly extendible arm about a universal joint allowing controlled pitch motion and controlled roll motion in said brick laying clamp relative to said arm, and said brick laying clamp is mounted to said universal joint on a rotatable mount for controlled rotation about a yaw axis.

14. A brick laying and adhesive applying head as claimed in claim 13 wherein said mount includes a mount pitch-axis allowing controlled pitch motion of said arm relative to said mount.

15. A brick laying and adhesive applying head as claimed in claim 13 or 14 wherein said universal joint has a first wrist-axis pivotable transverse to the longitudinal extent of said arm and a second wrist-axis disposed normal to said first wrist axis, both wrist-axes being normal to said yaw axis.

16. A brick laying and adhesive applying head as claimed in any one of claims 13 to 15 wherein said linearly extending arm includes a linear guide which connects with said mount for controlled linear movement to extend and retract said arm in order to move said brick laying clamp toward or away from said mount.

17. A brick laying and adhesive applying head as claimed in any one of claims 13 to 16 wherein the brick laying clamp includes jaws that are independently moveable to clamp and unclamp a brick, and also selectively moveable in unison to offset the position of the jaws relative to the brick laying clamp.

18. A brick laying and adhesive applying head as claimed in any one of claims 11 to 17 wherein said adhesive applicator tool is as claimed in any one of claims 1 to 10, wherein said adhesive applicator tool is configured to retract said tongue within said sheath to withdraw said adhesive applicator away from said pivotable clamp, and said sheath is aligned extending away from said horizontal axis, and substantially along said clevis toward said mount, to provide clearance between said sheath and said brick laying head in order to allow operation without interference.

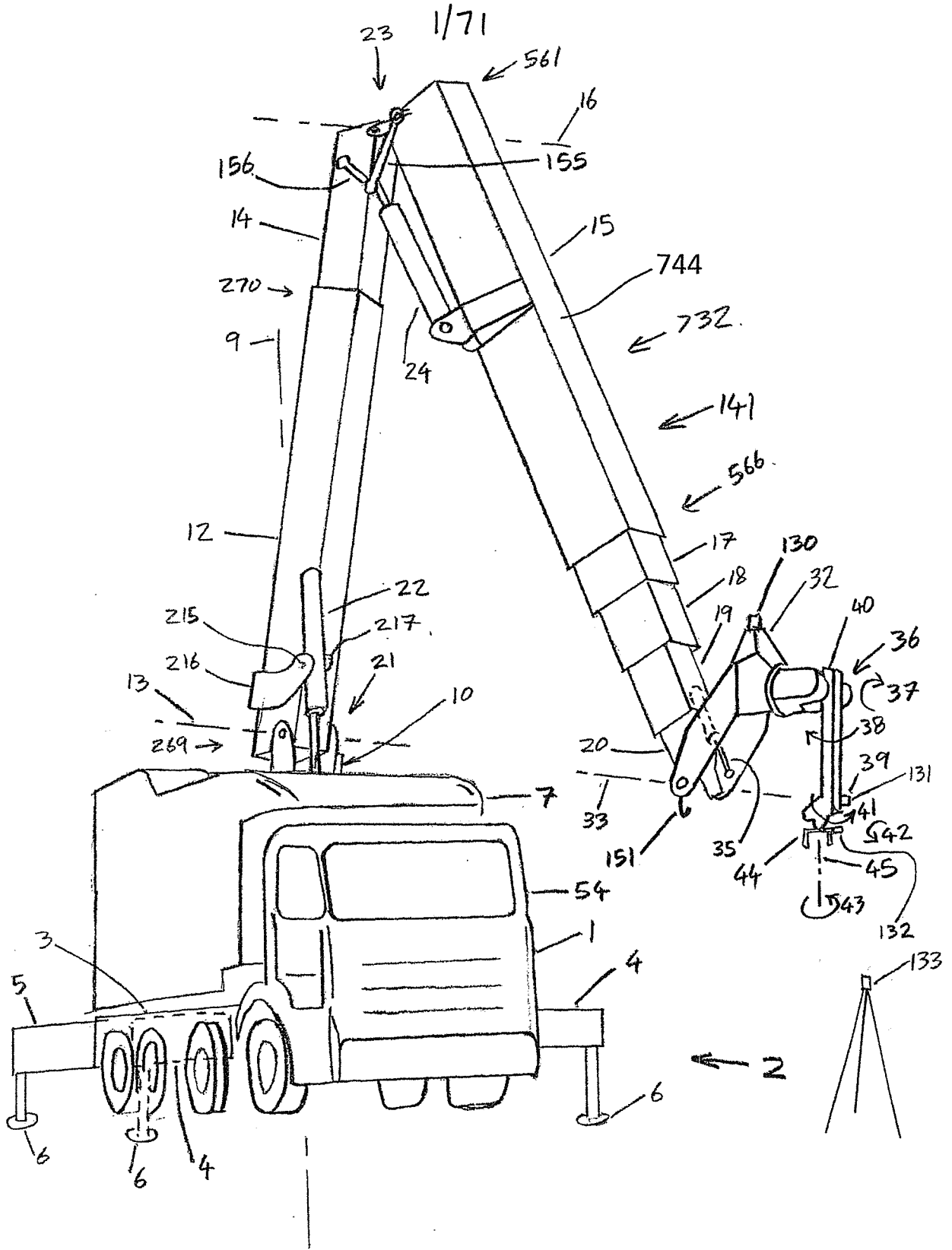


Figure 1

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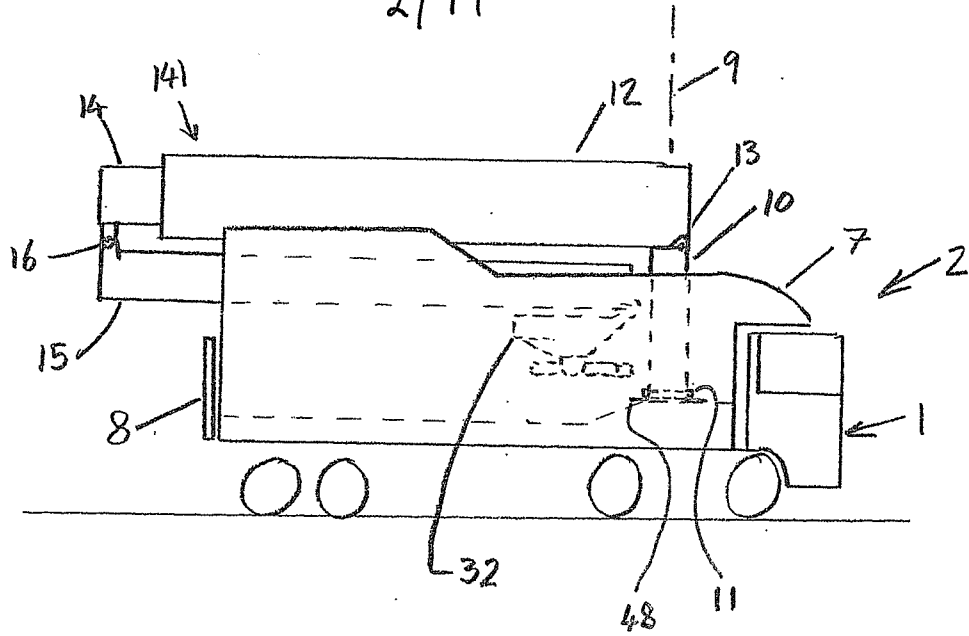


Figure 2

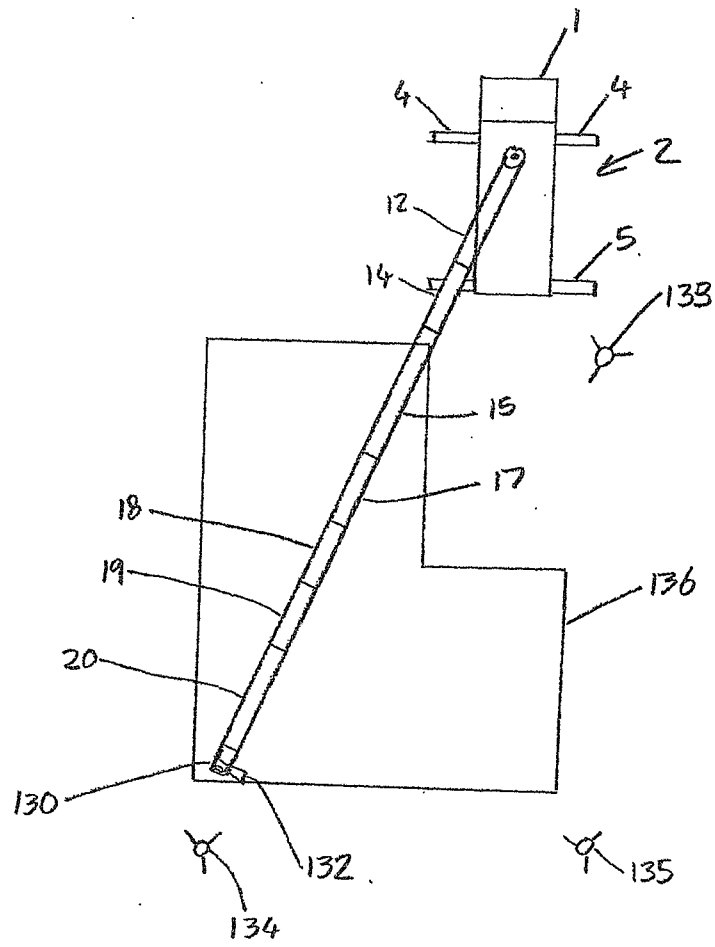


Figure 3

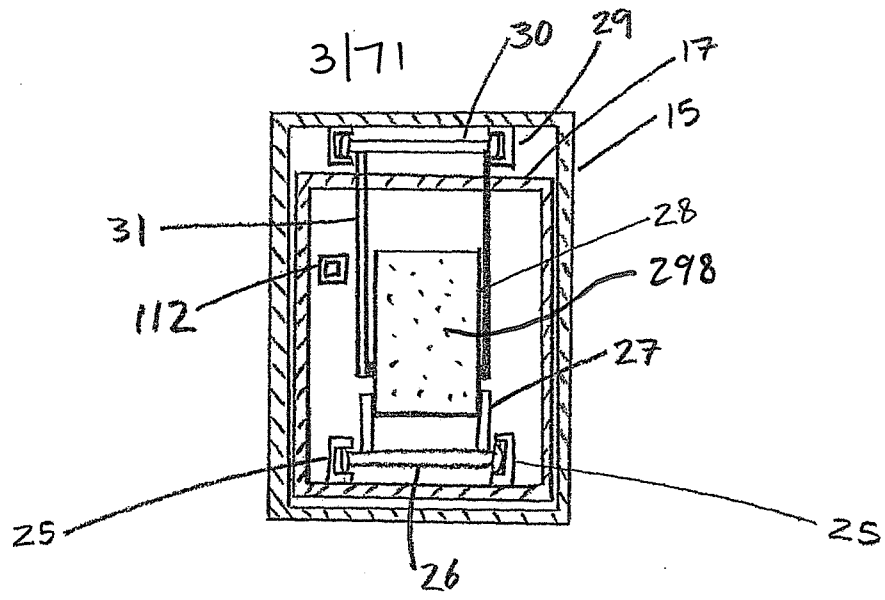


Figure 4

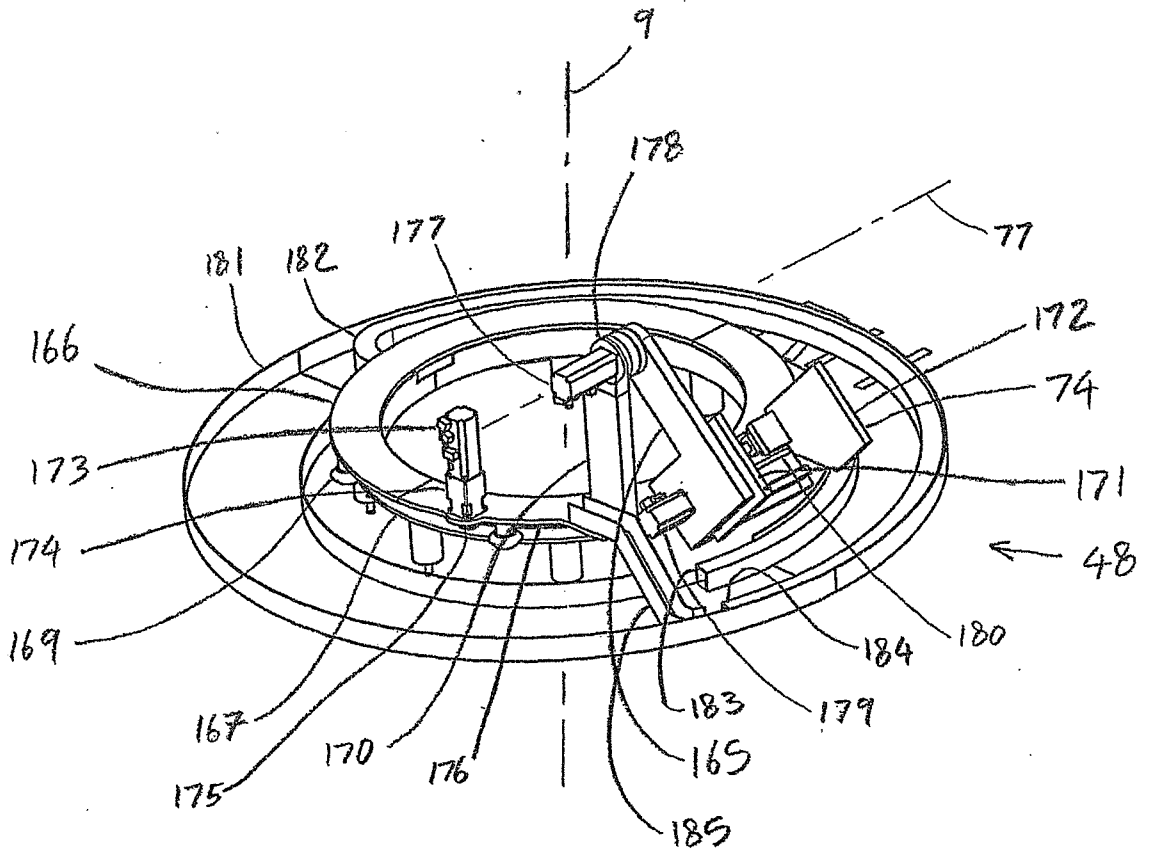


Figure 7

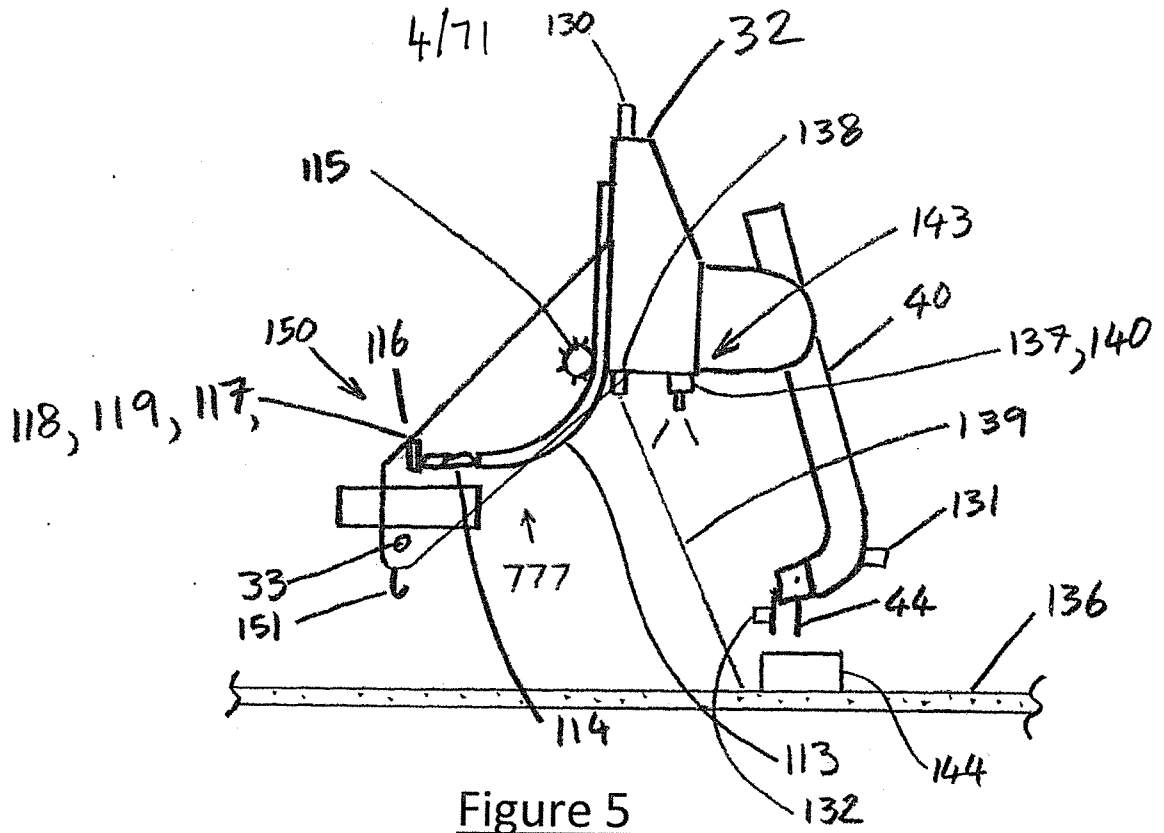


Figure 5

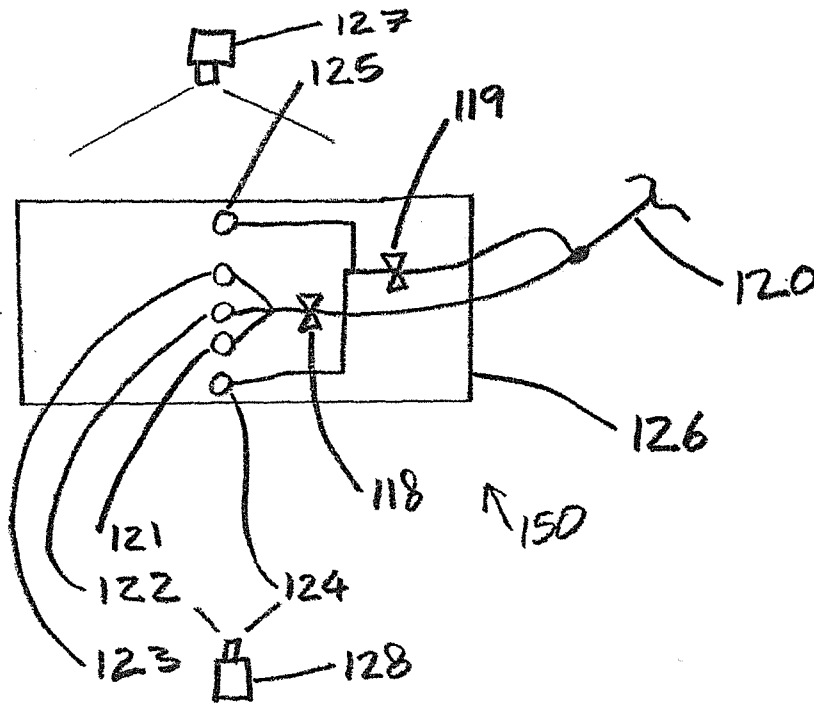


Figure 6

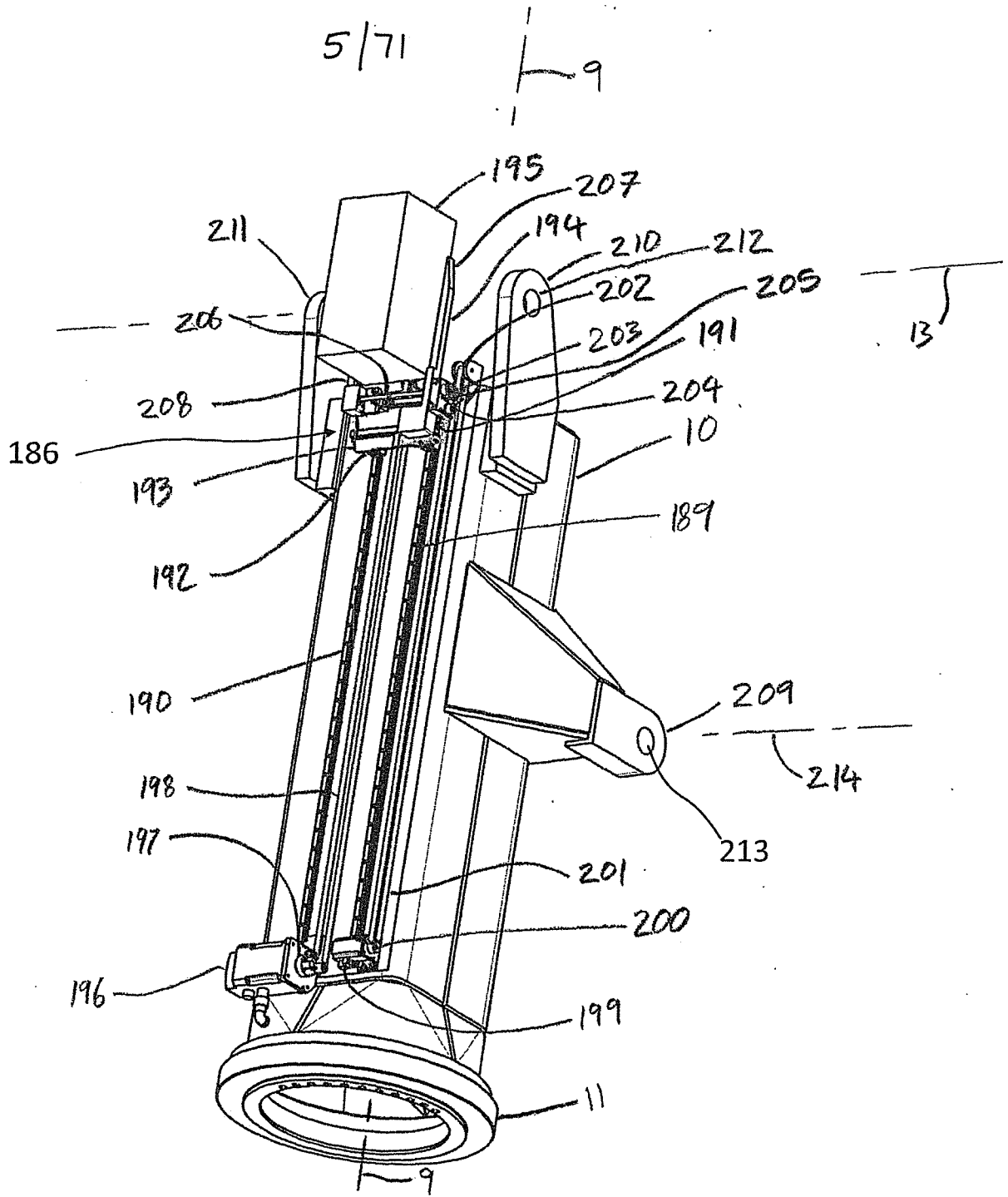


Figure 8

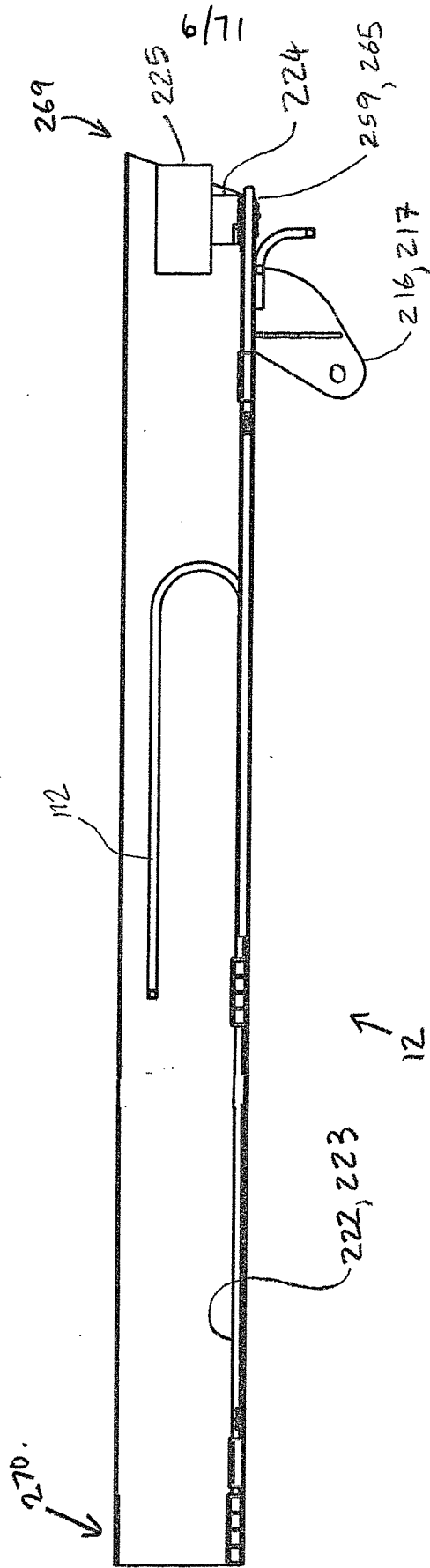
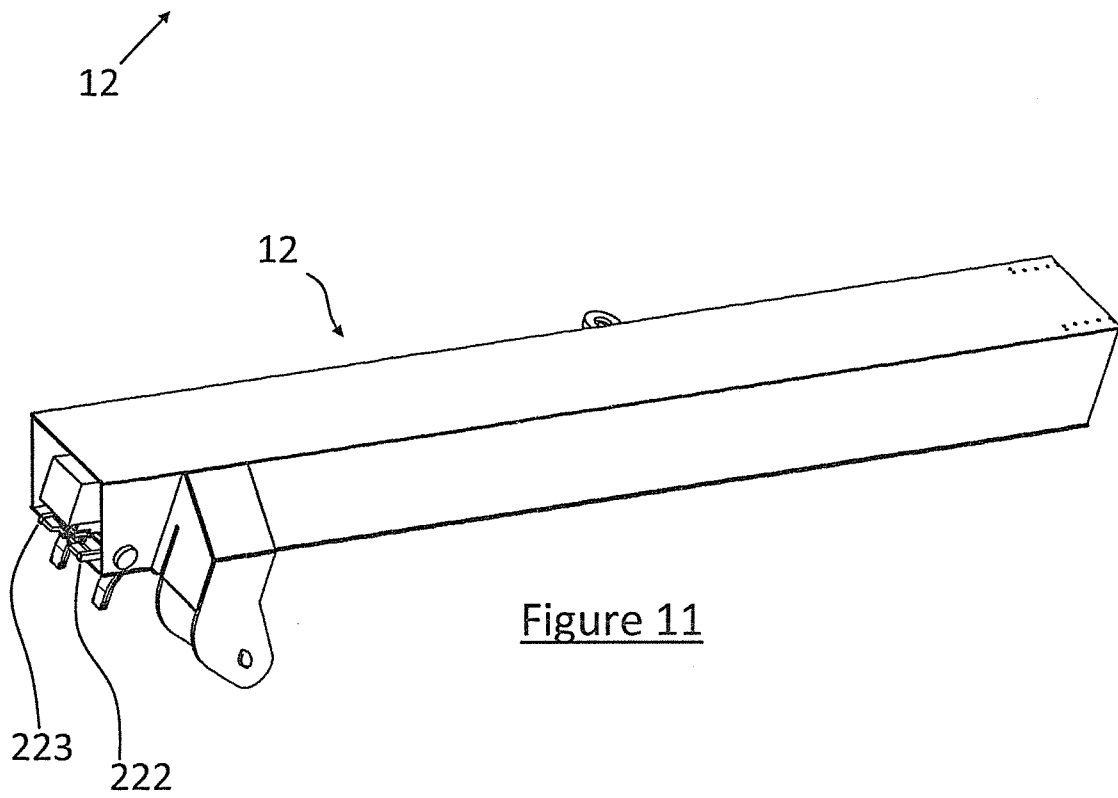
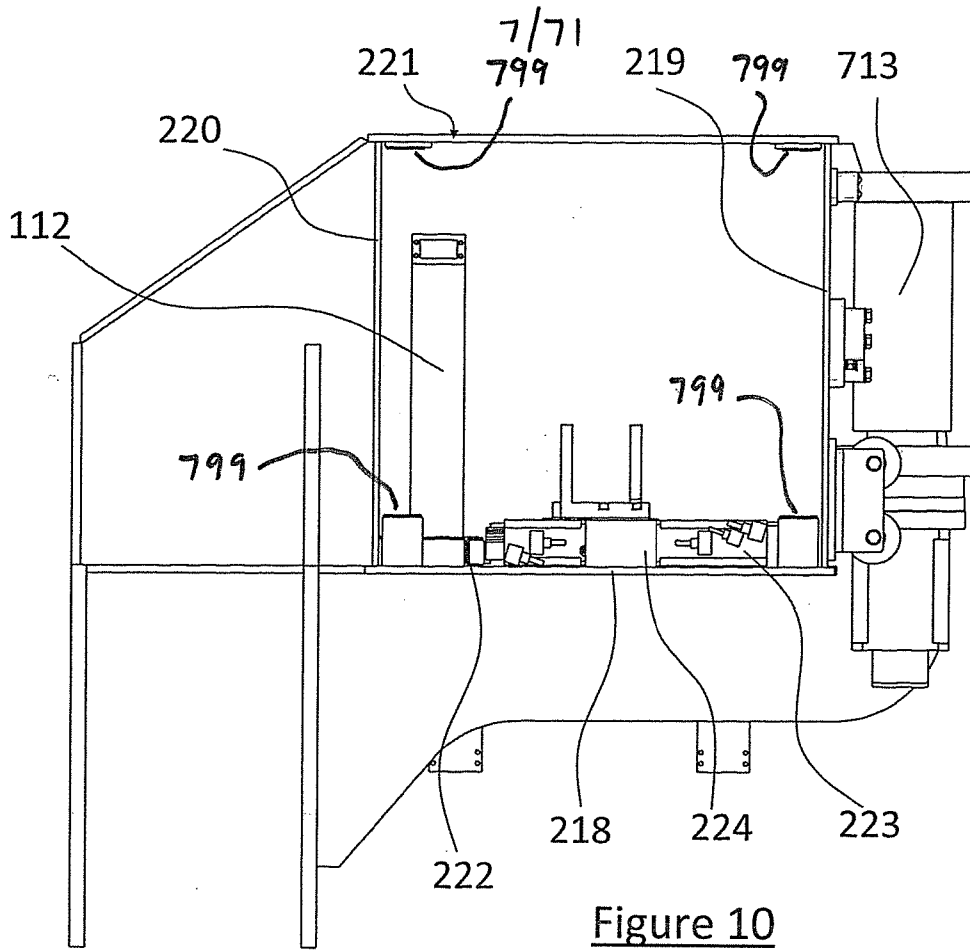


Figure 9



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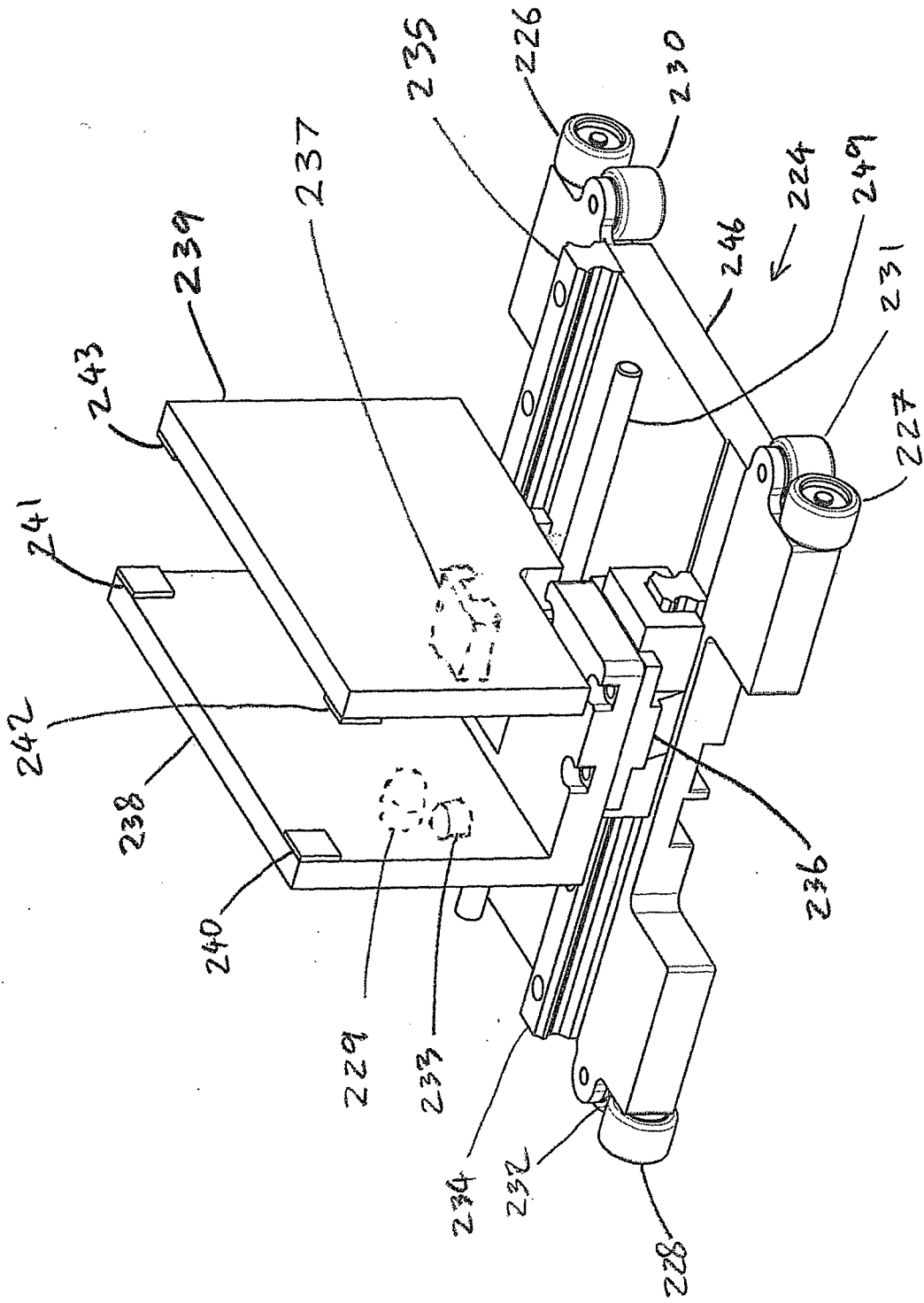


Figure 12

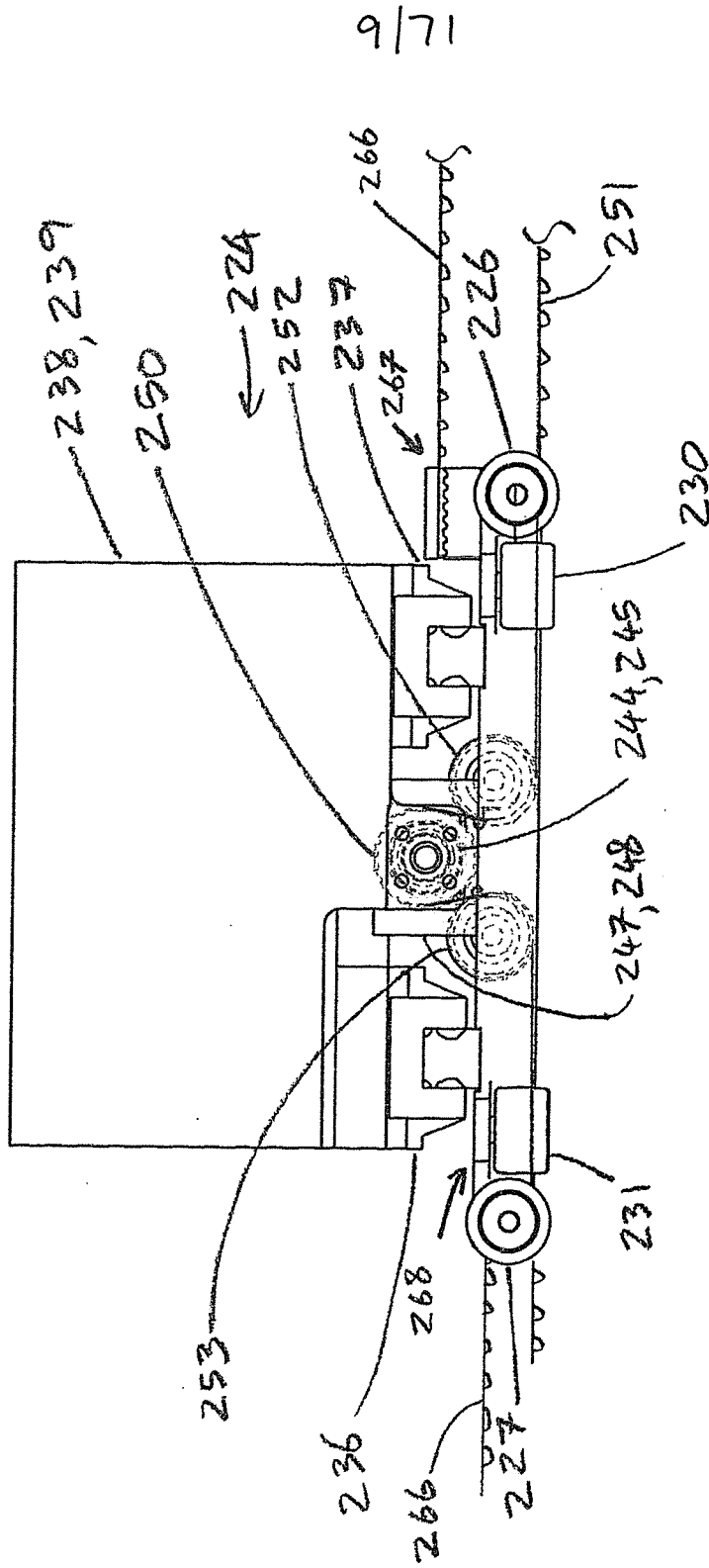


Figure 13

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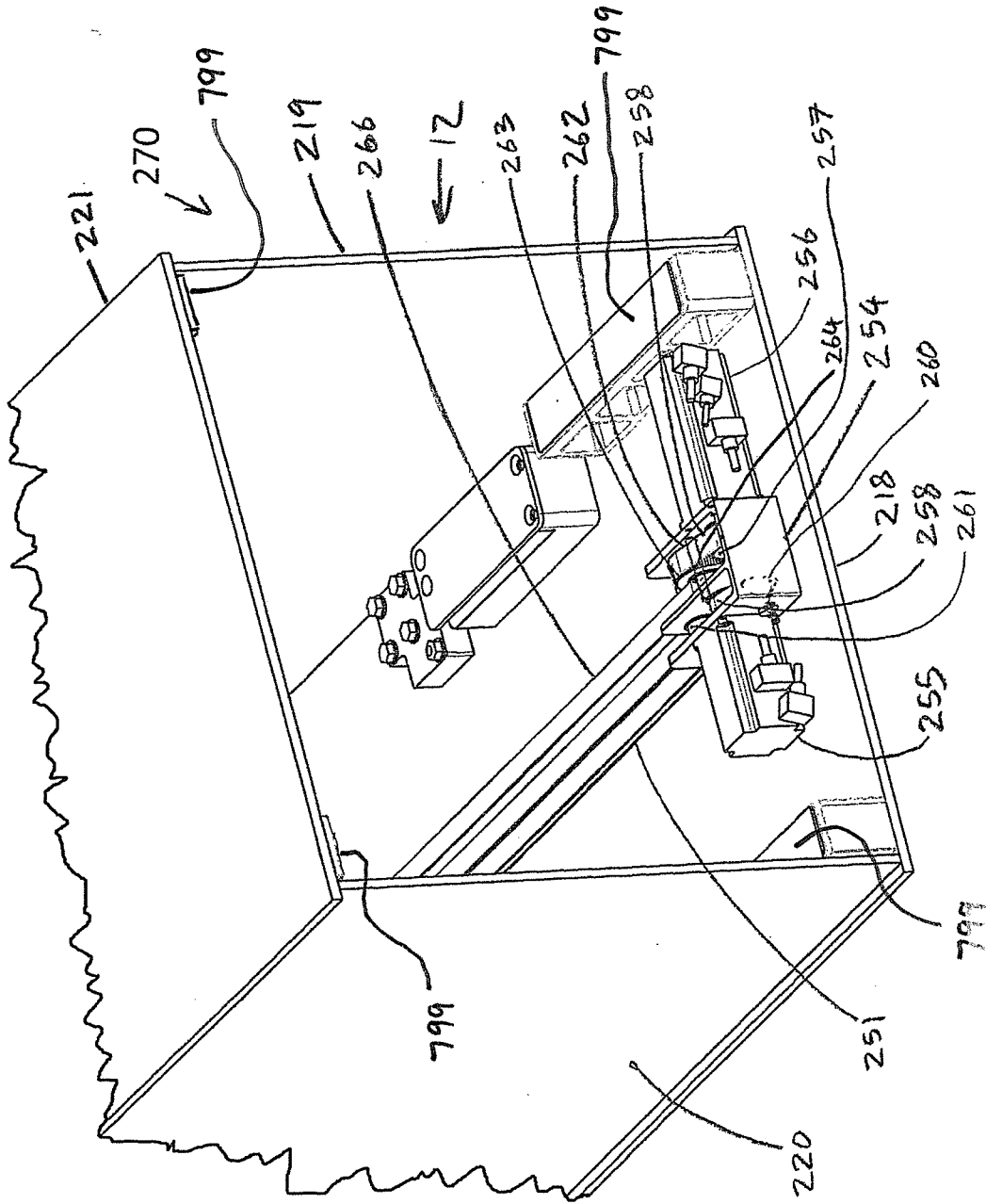


Figure 14

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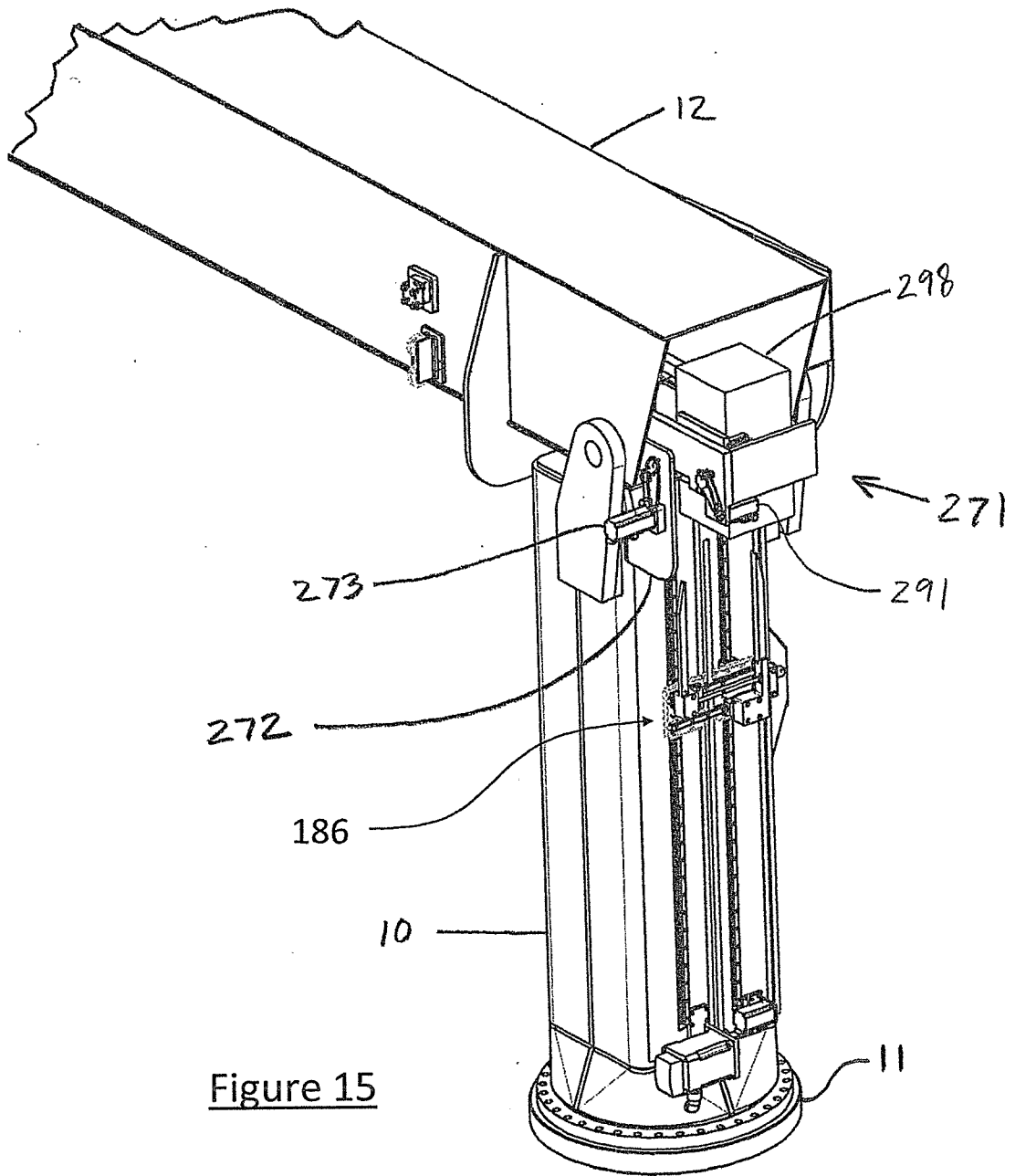


Figure 15

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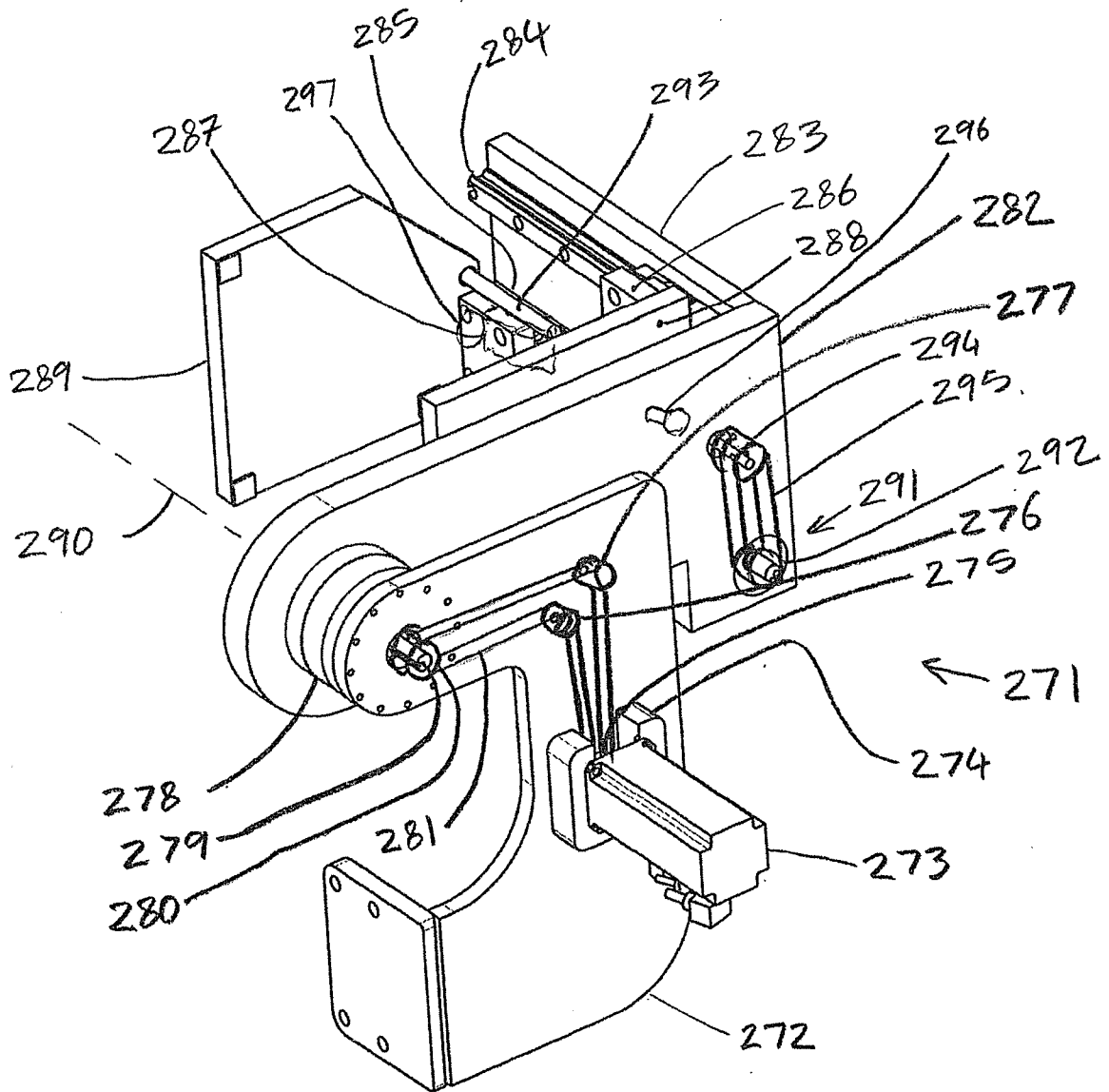


Figure 16

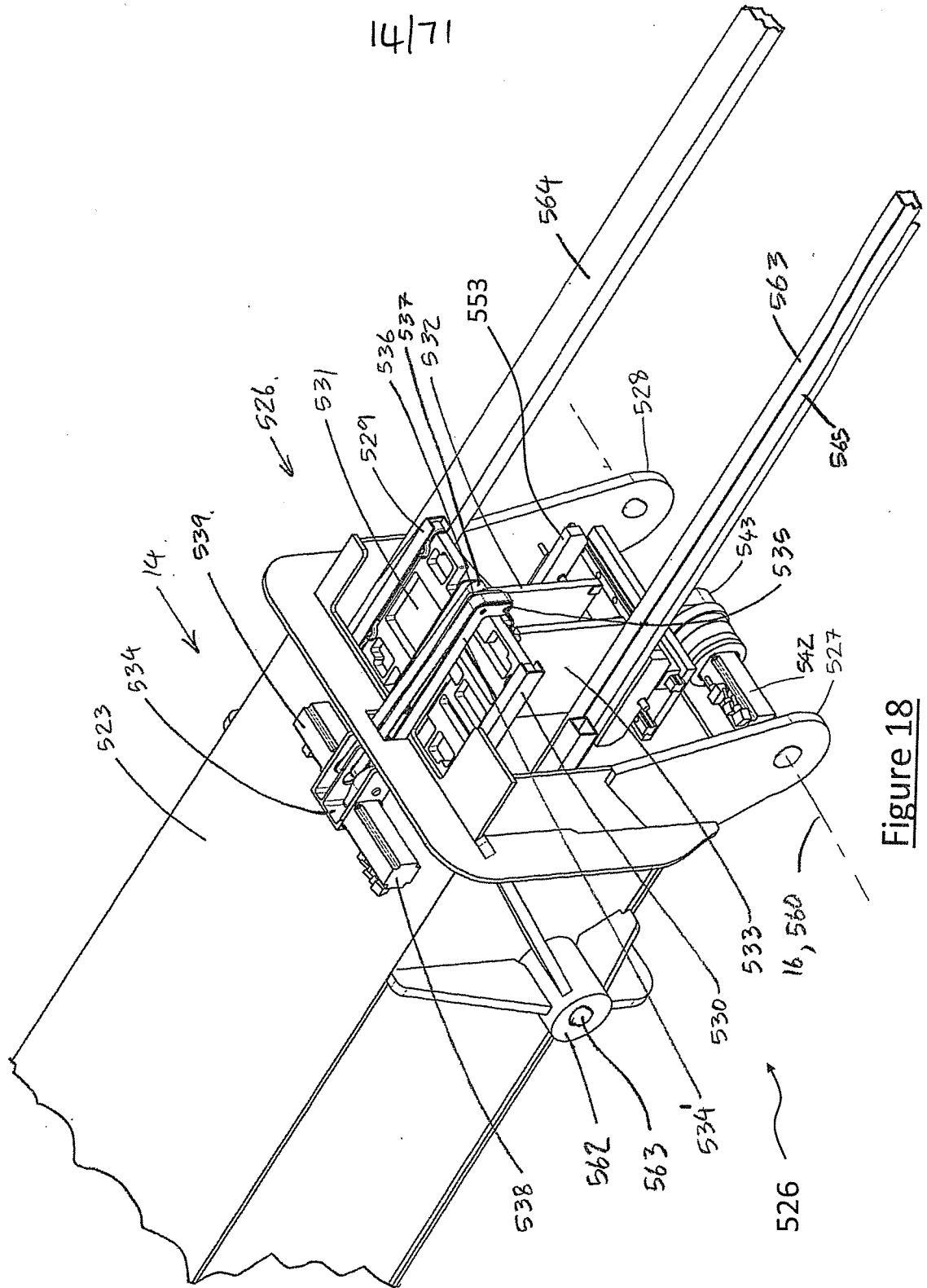


Figure 18

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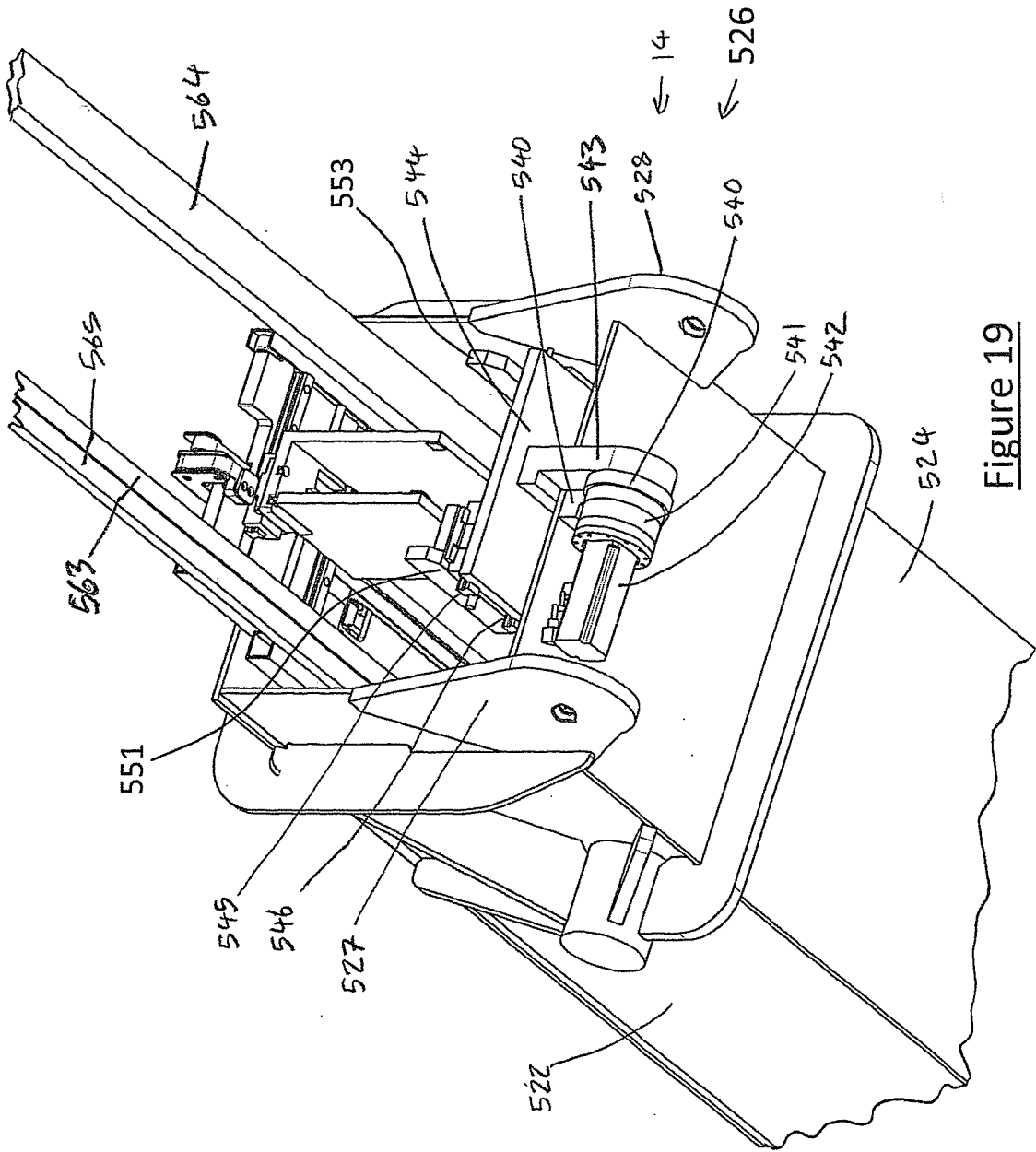


Figure 19

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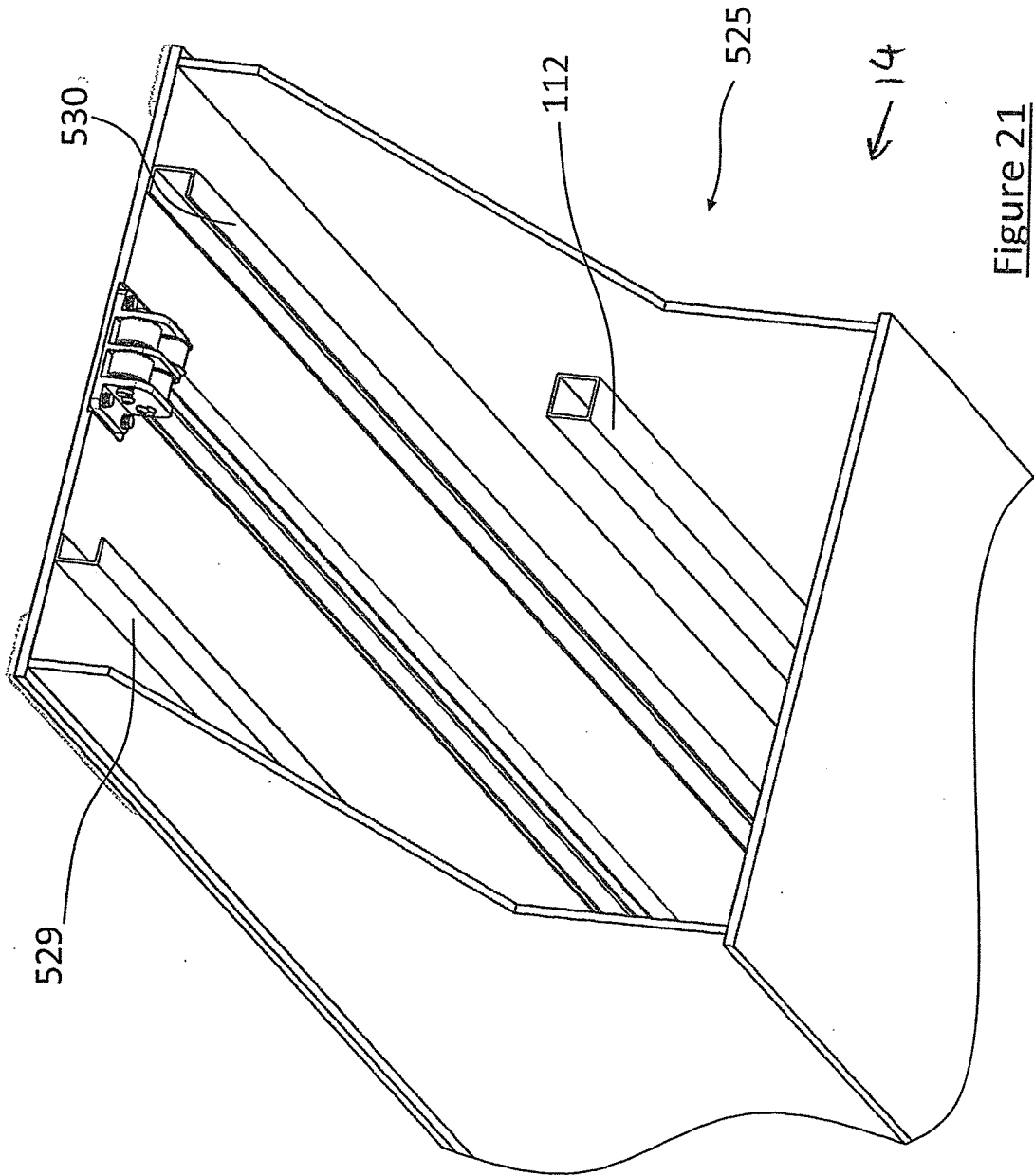
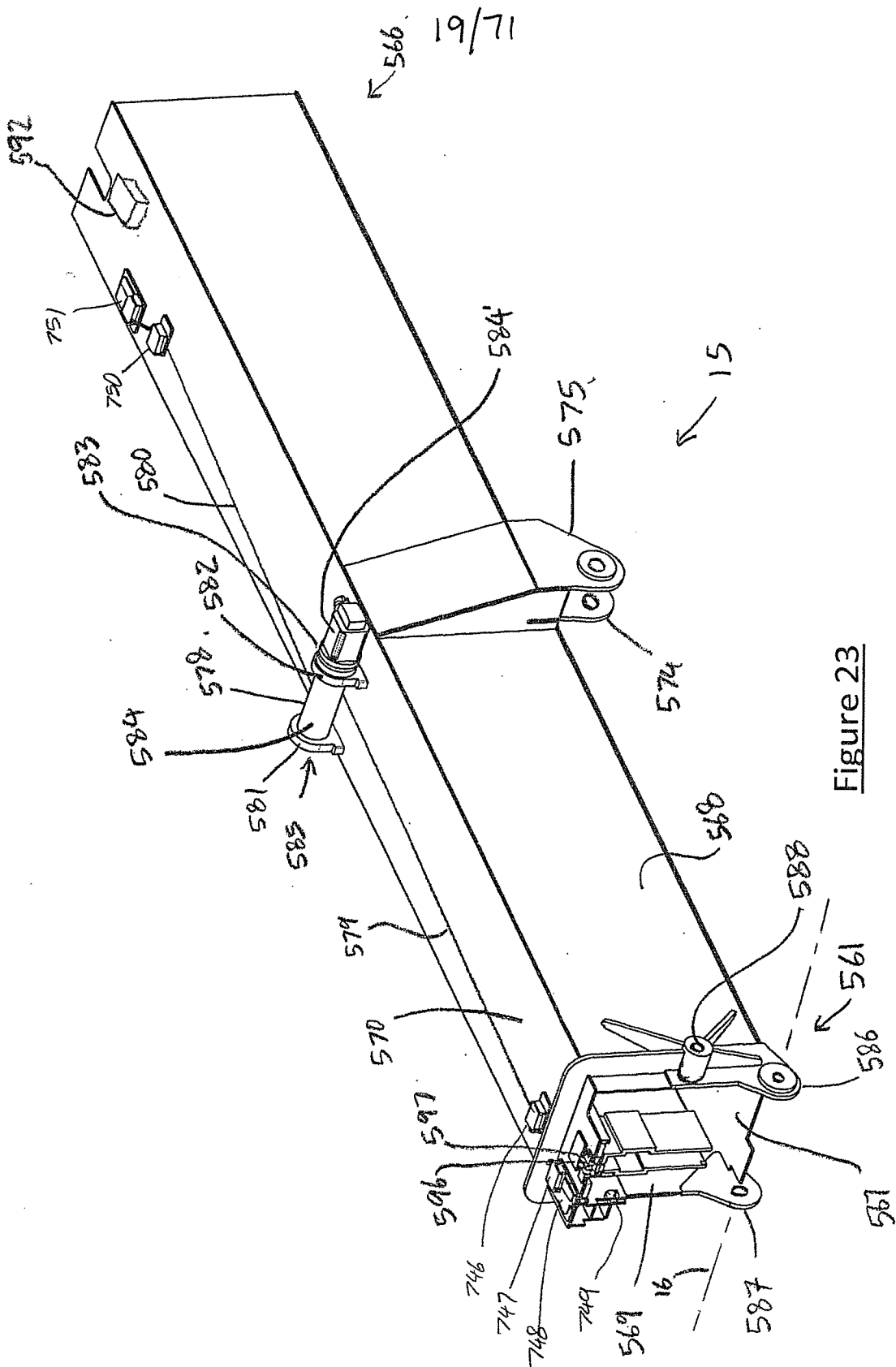


Figure 21



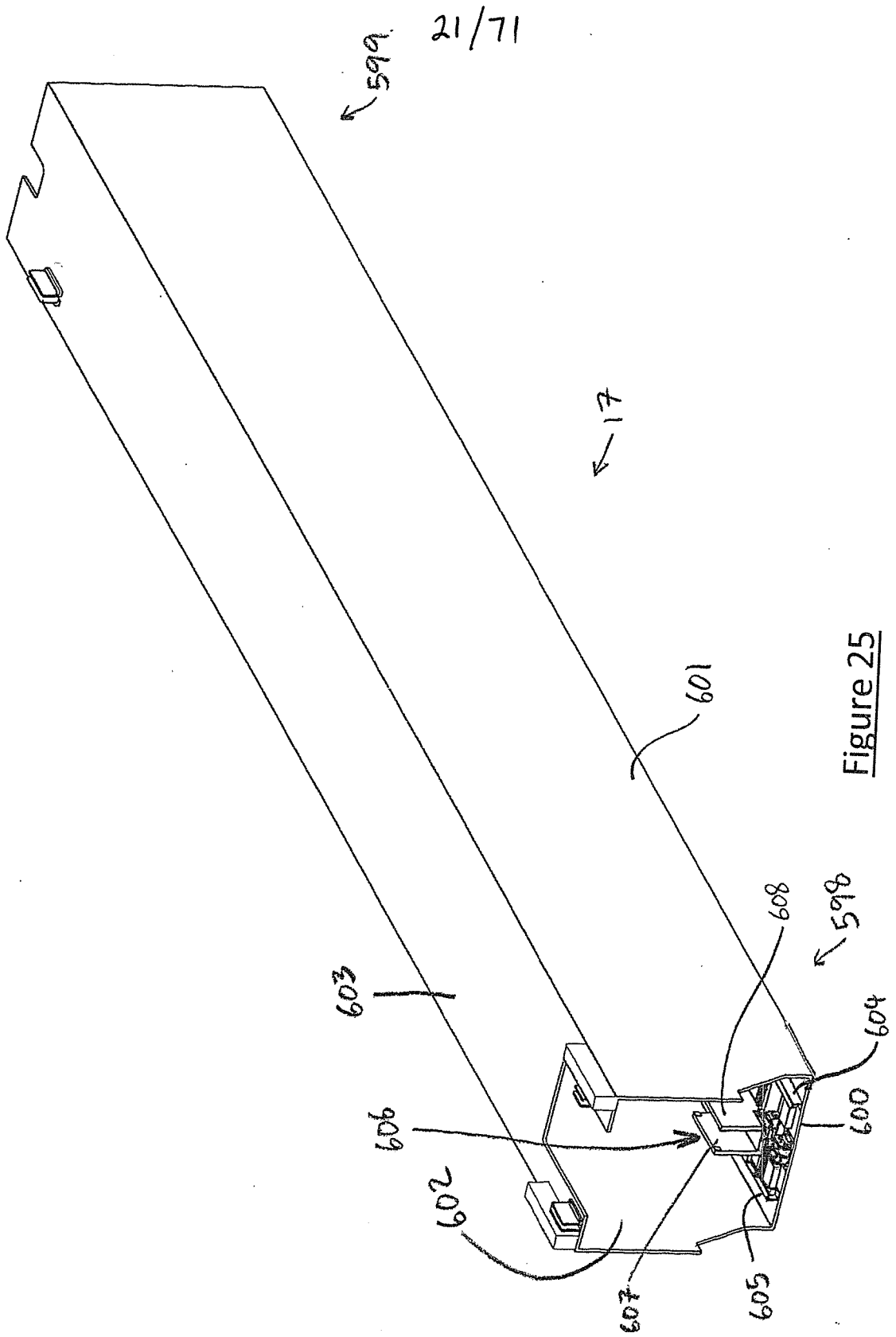


Figure 25

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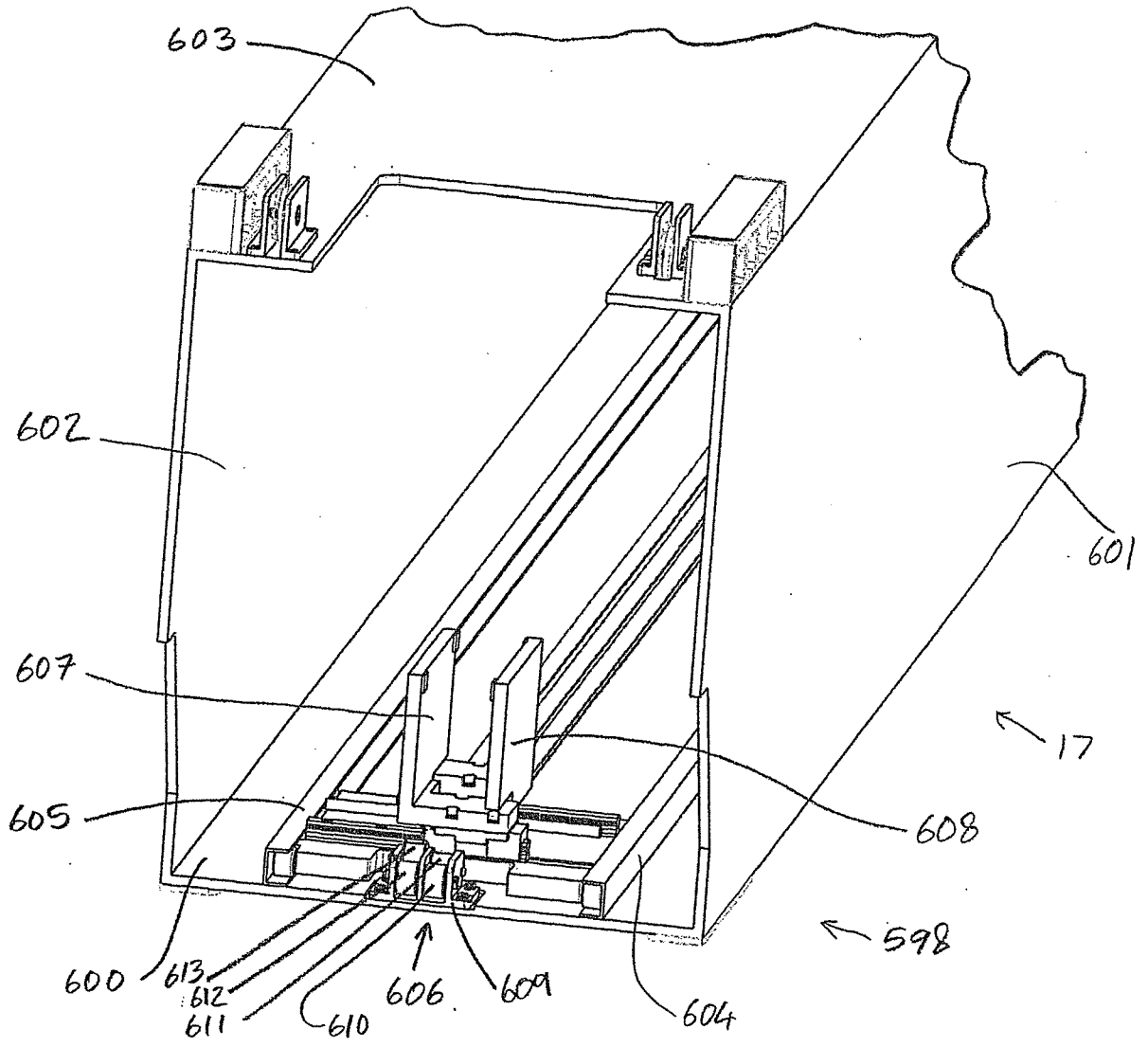


Figure 26

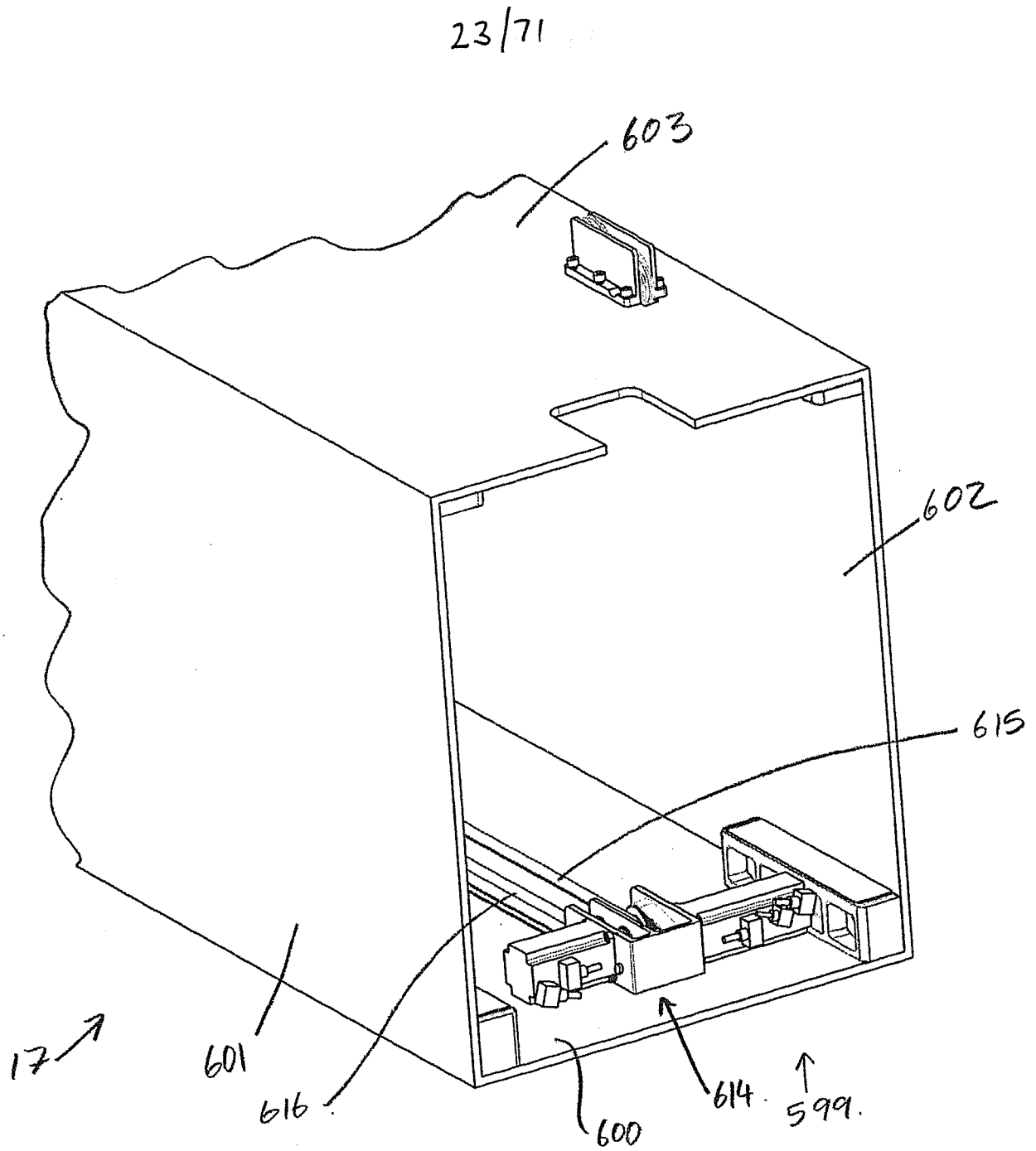


Figure 27

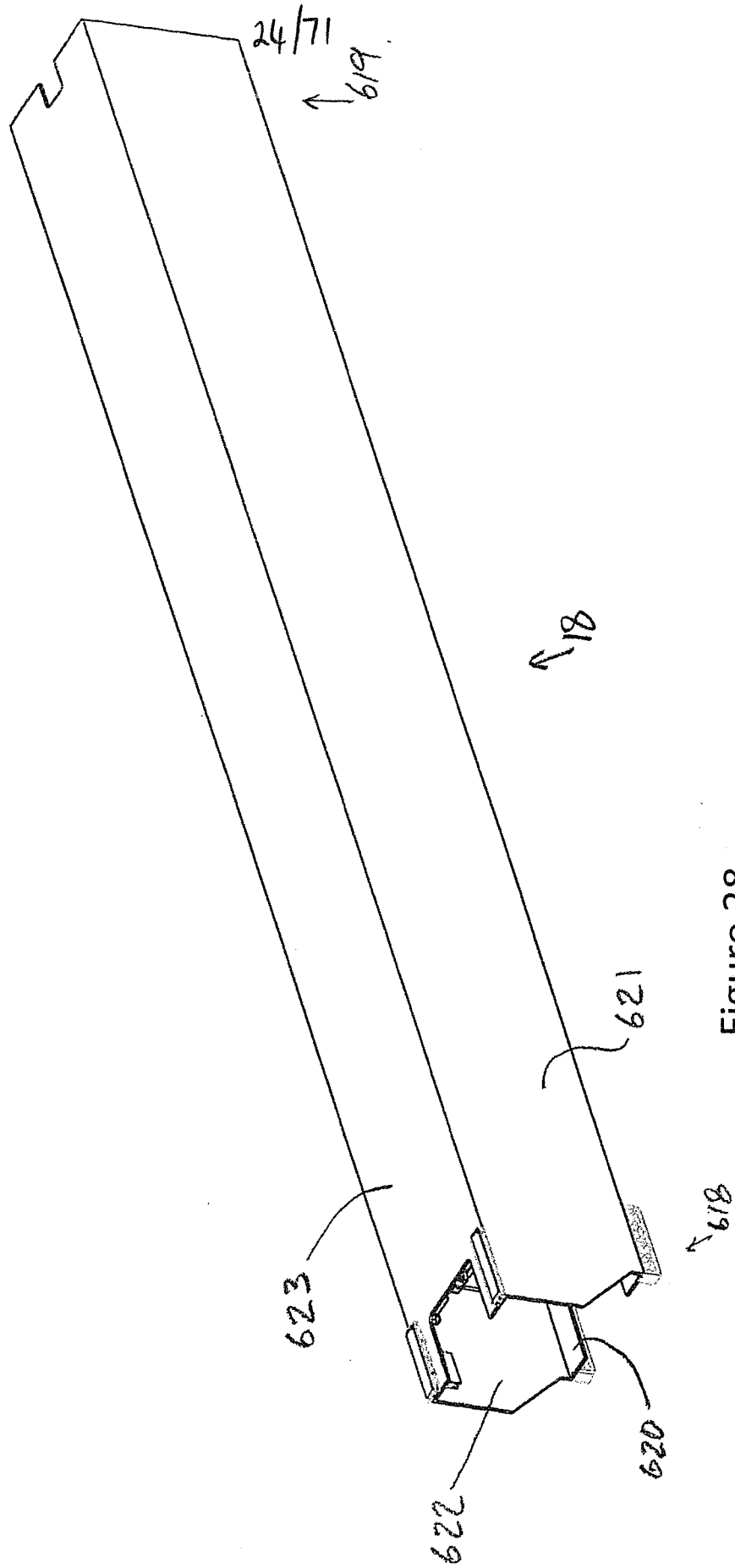


Figure 28

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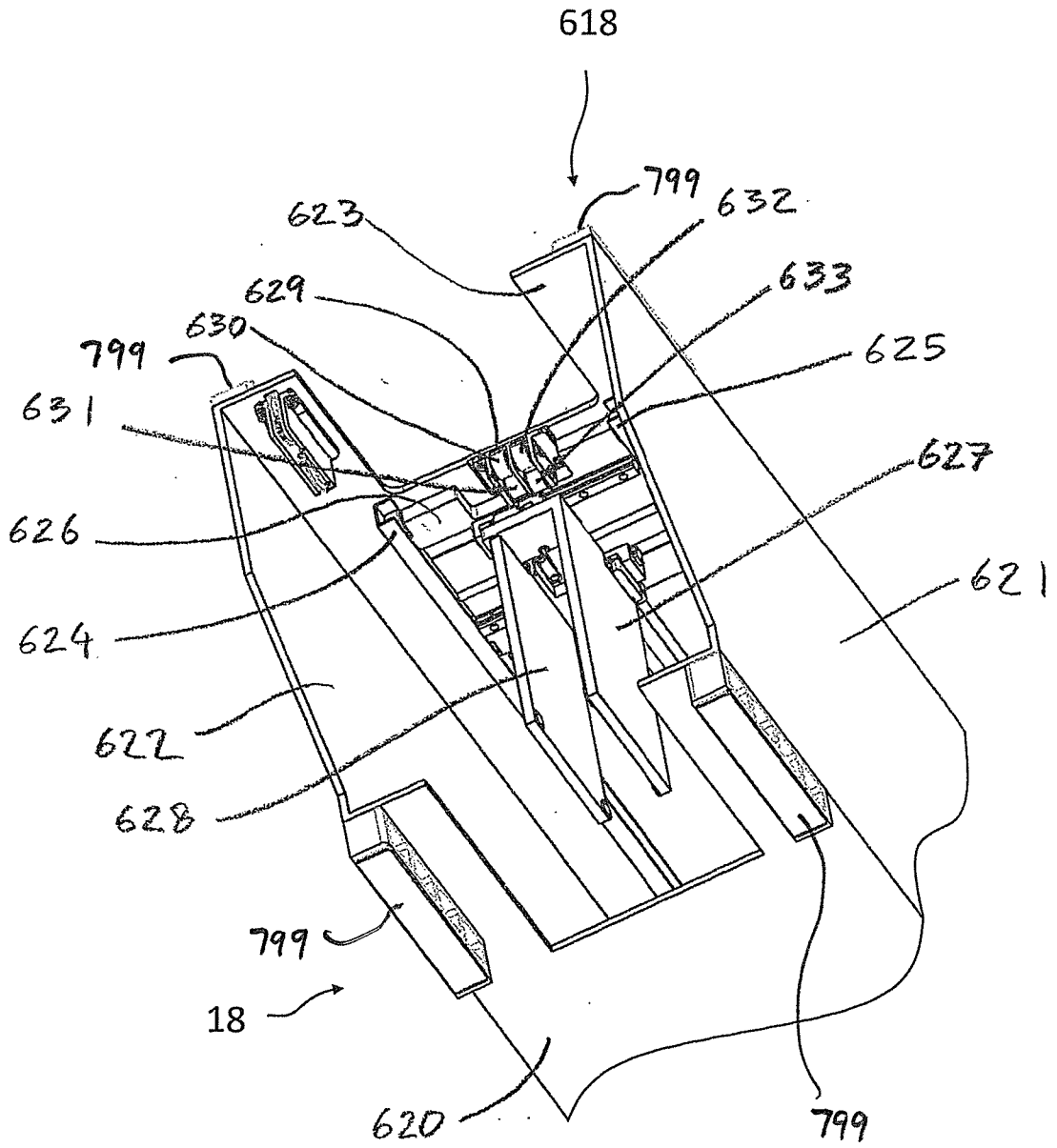


Figure 29

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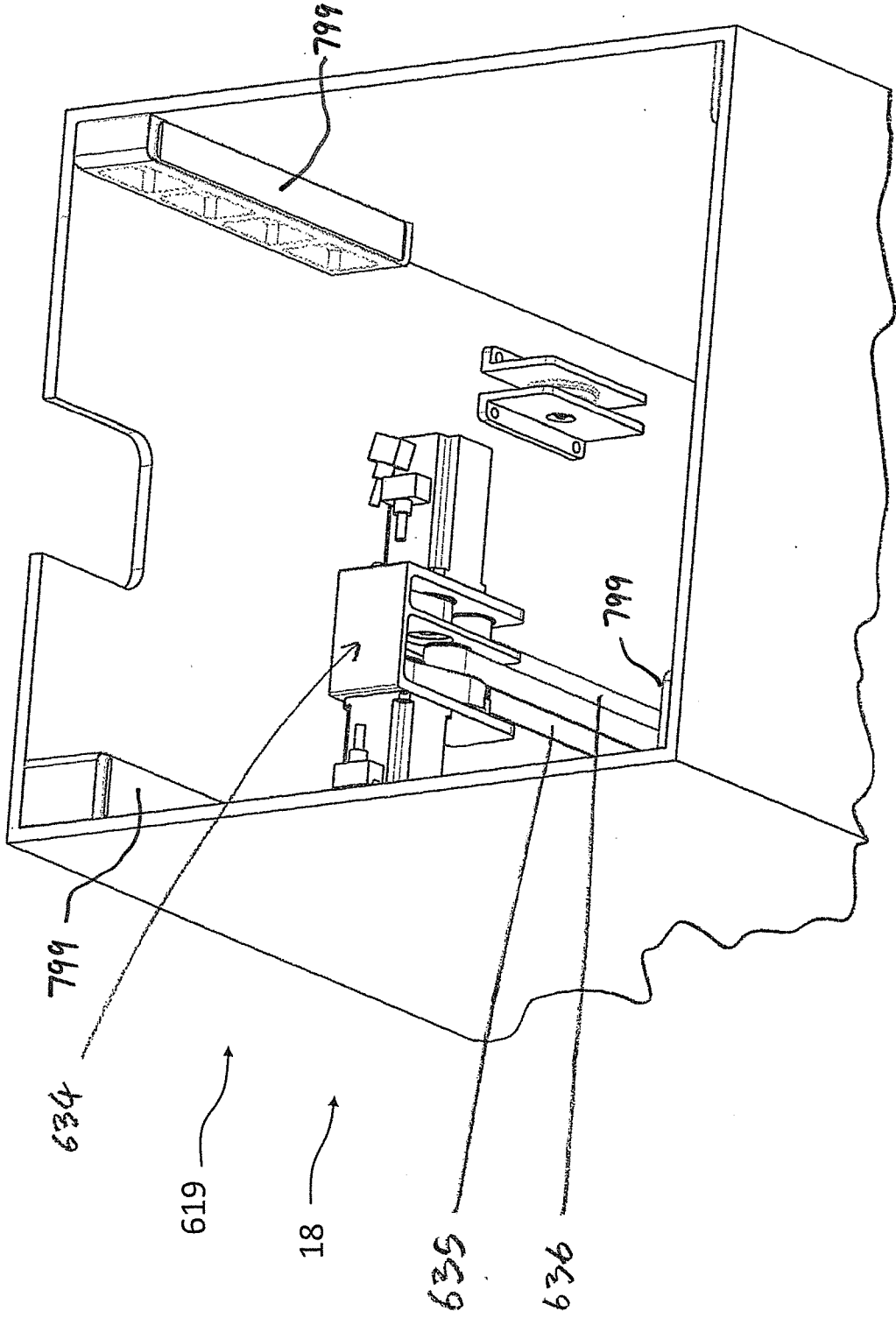


Figure 30

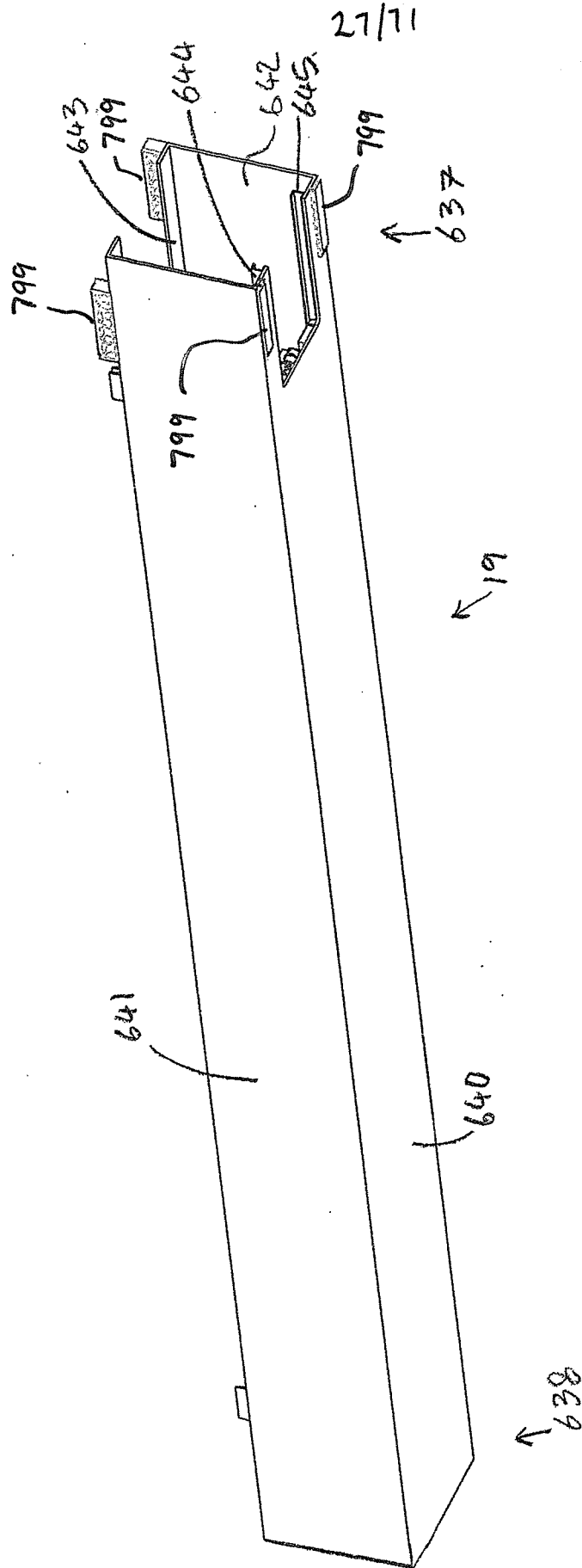


Figure 31

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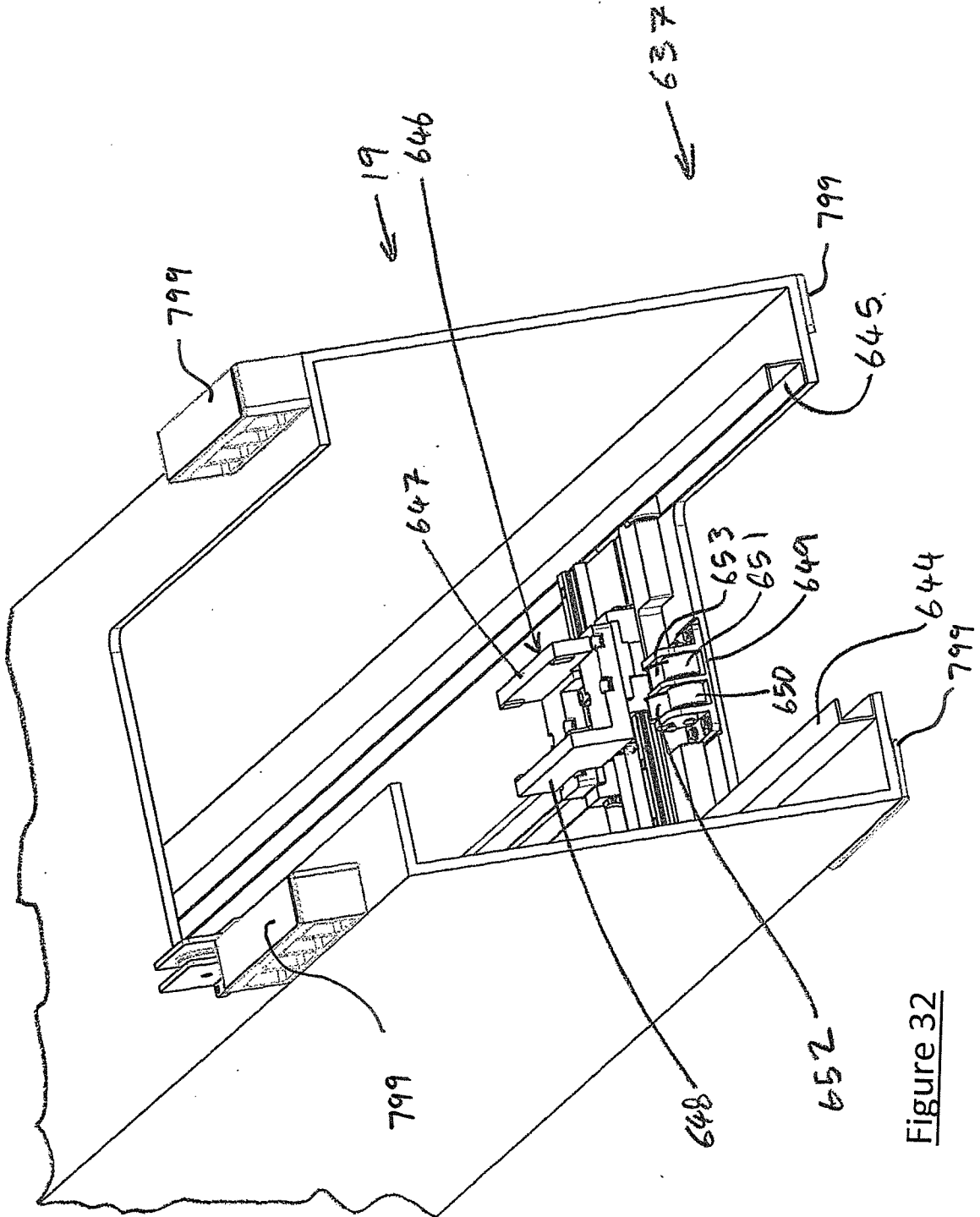
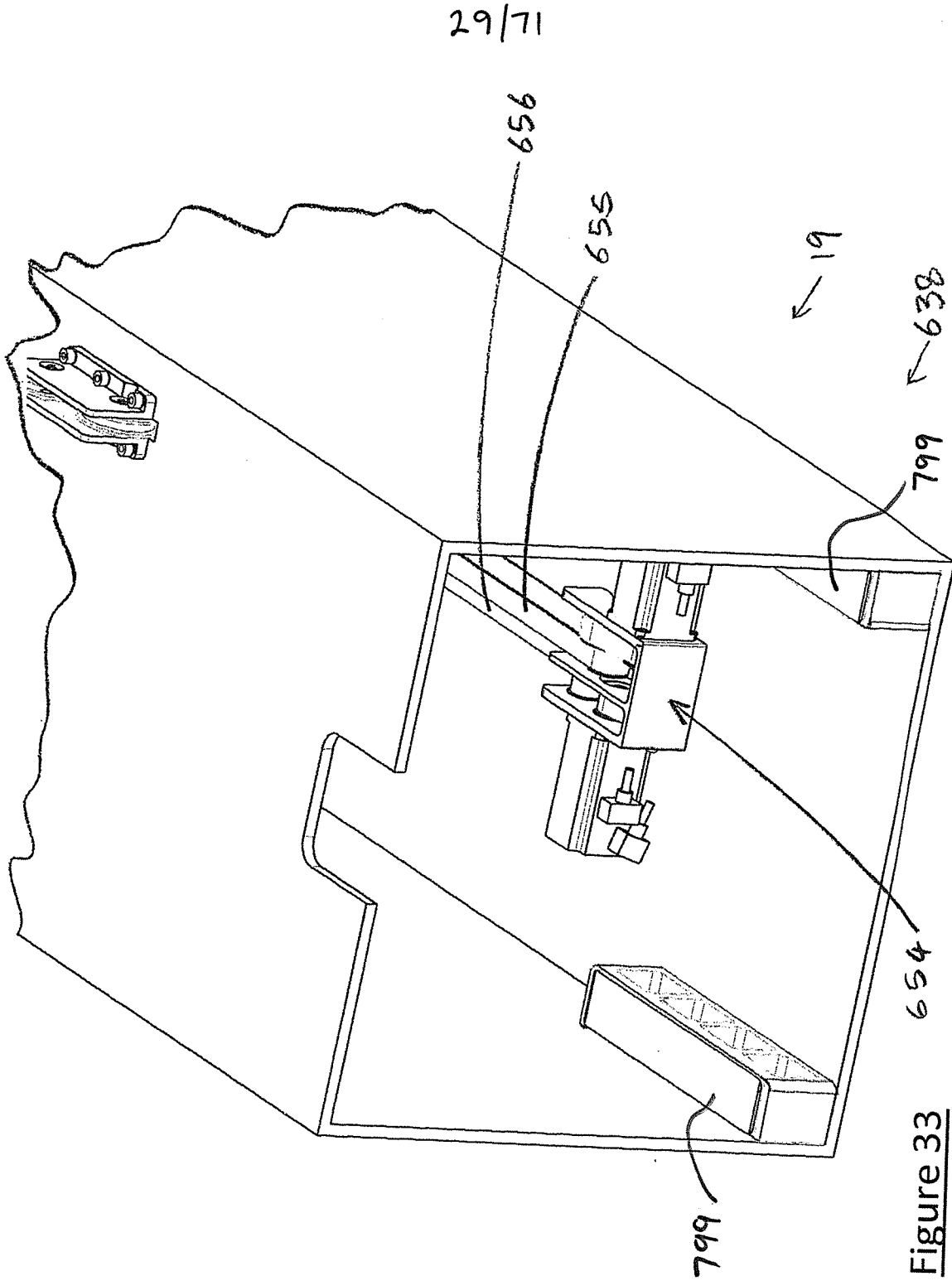


Figure 32



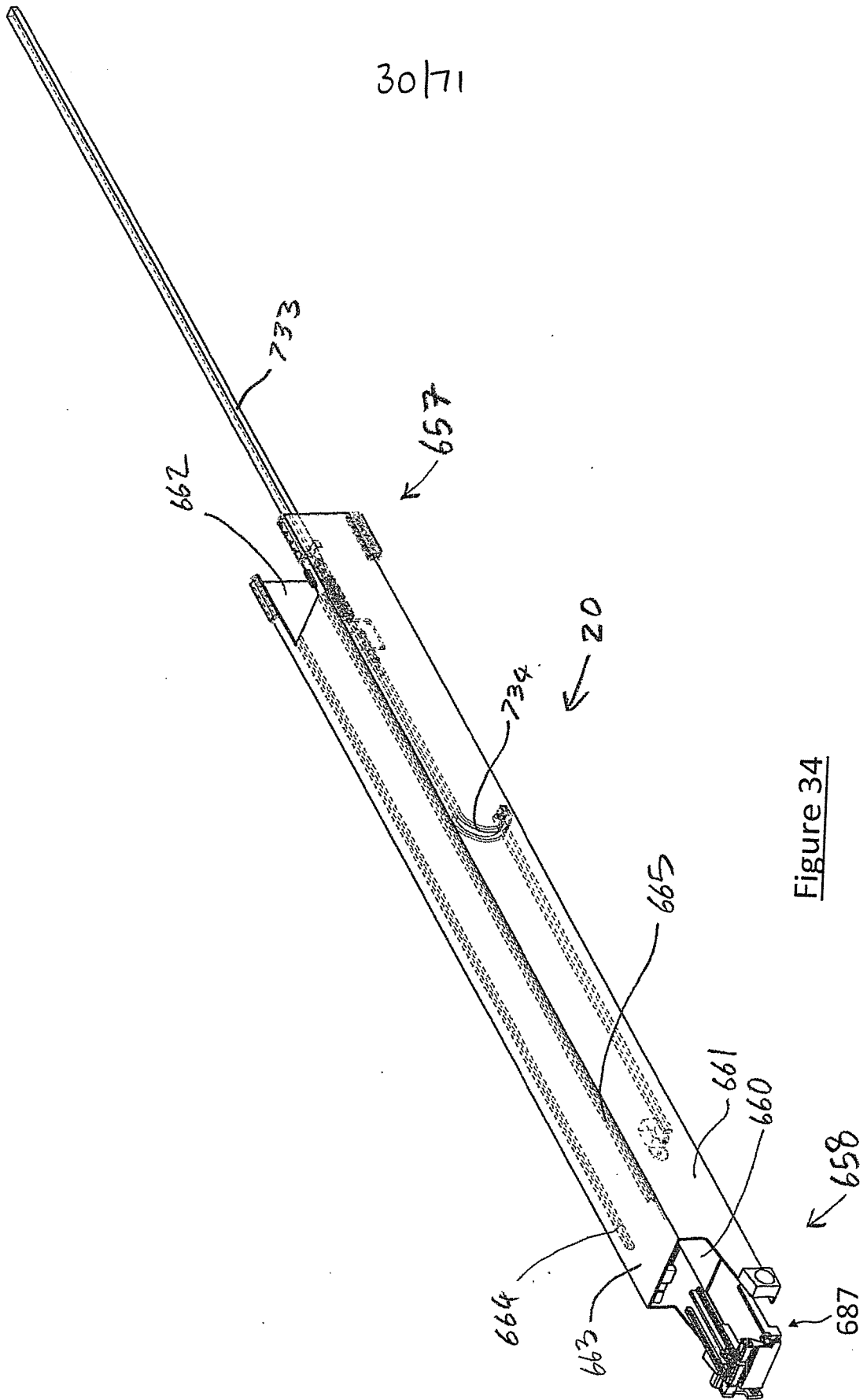


Figure 34

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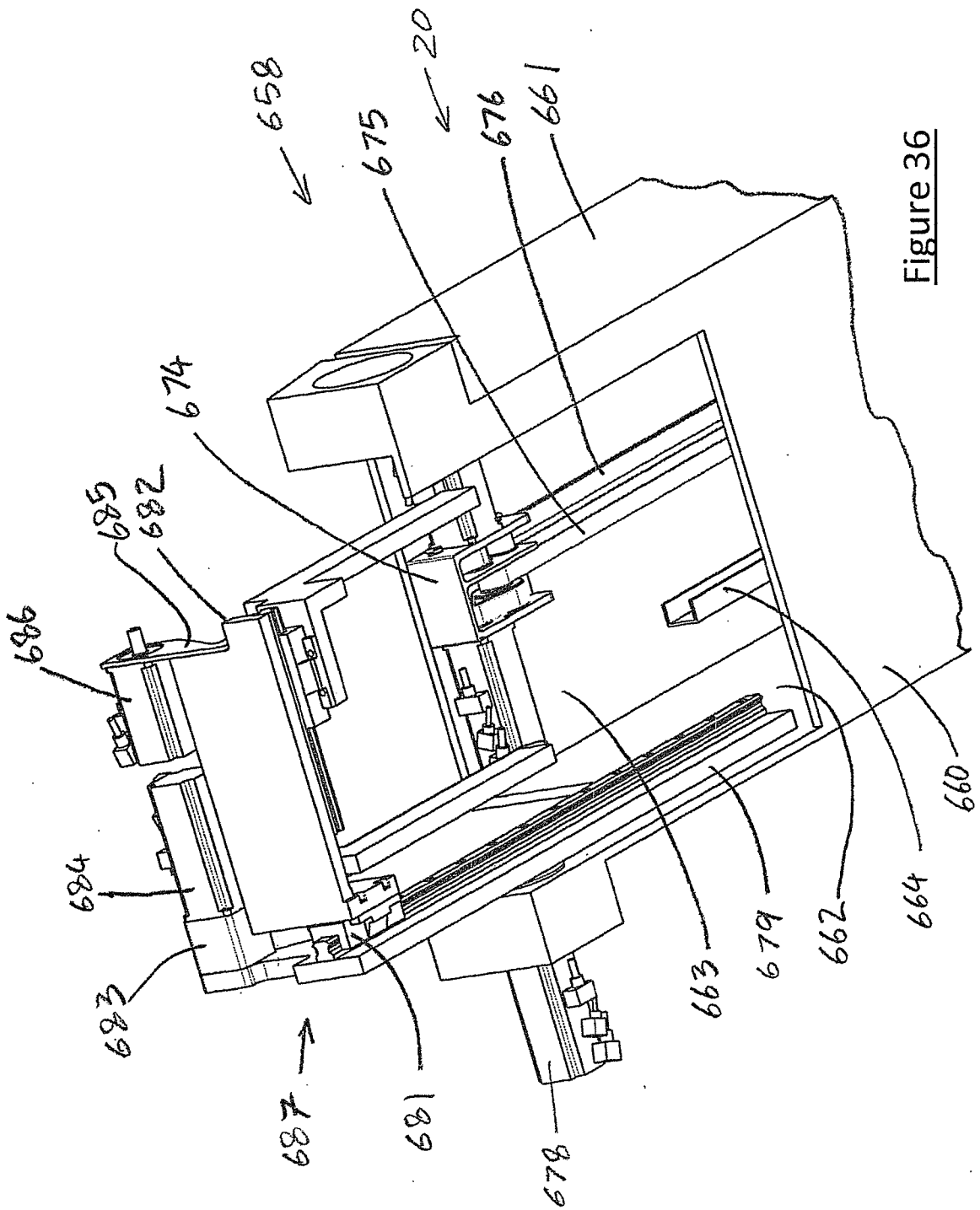


Figure 36

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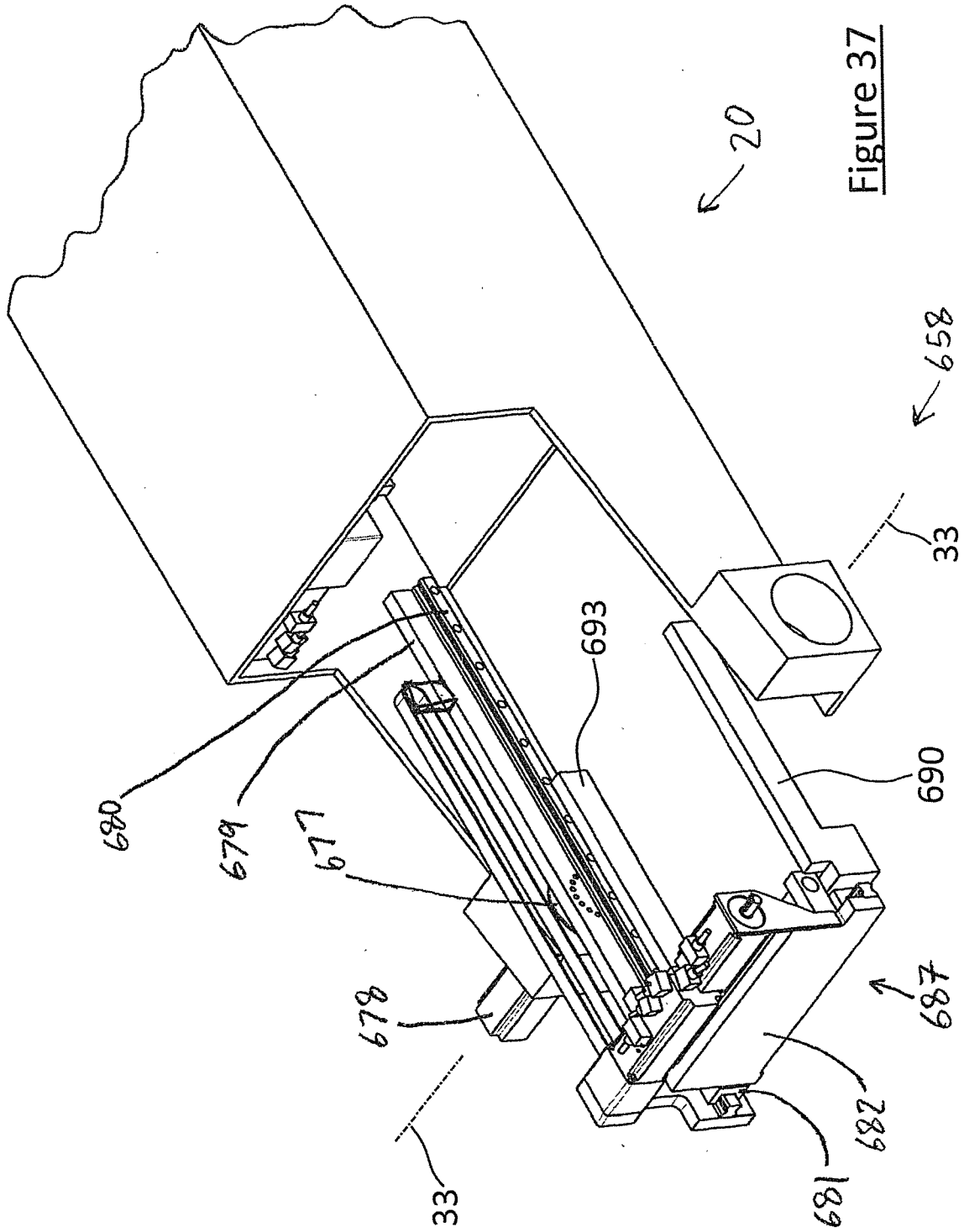


Figure 37

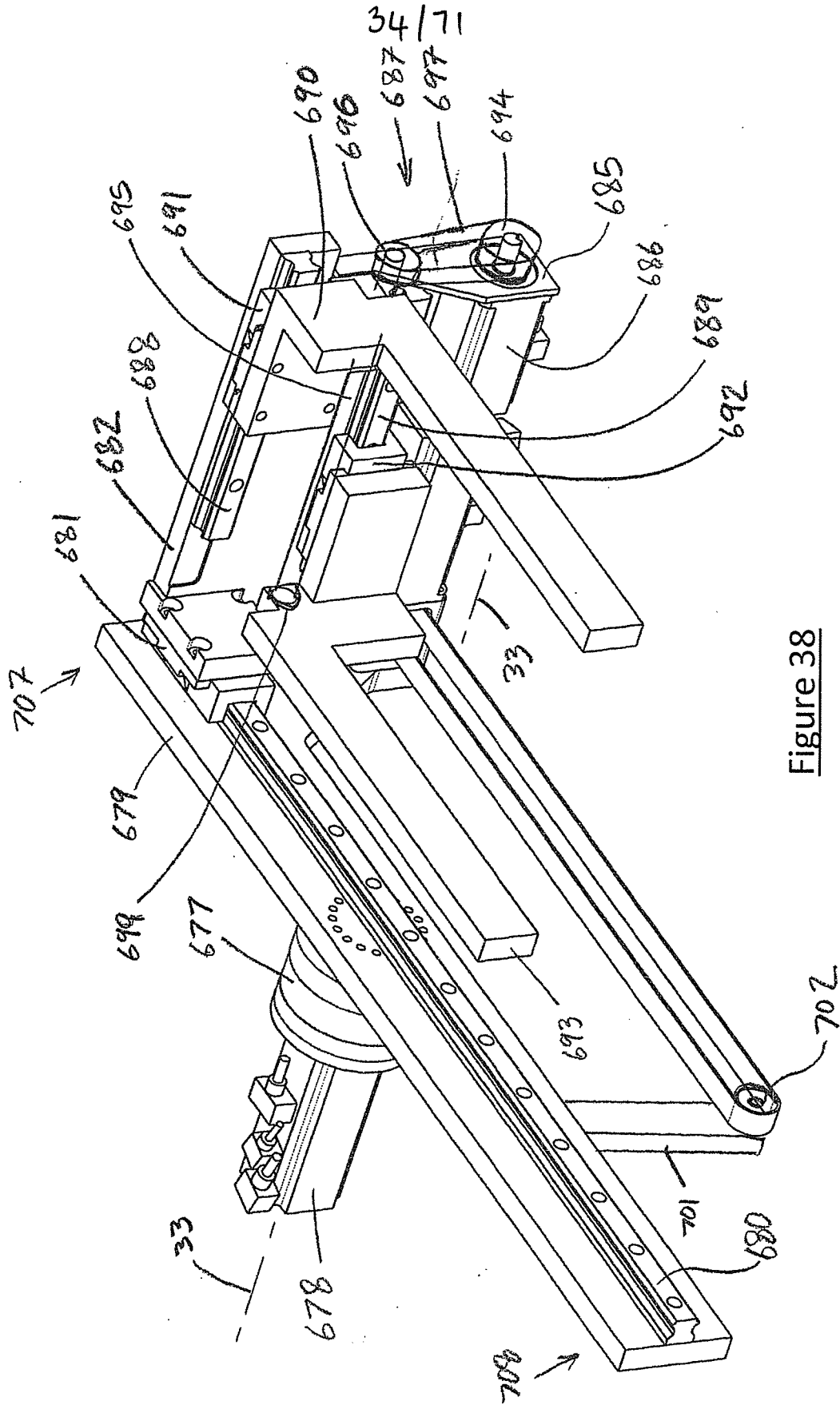


Figure 38

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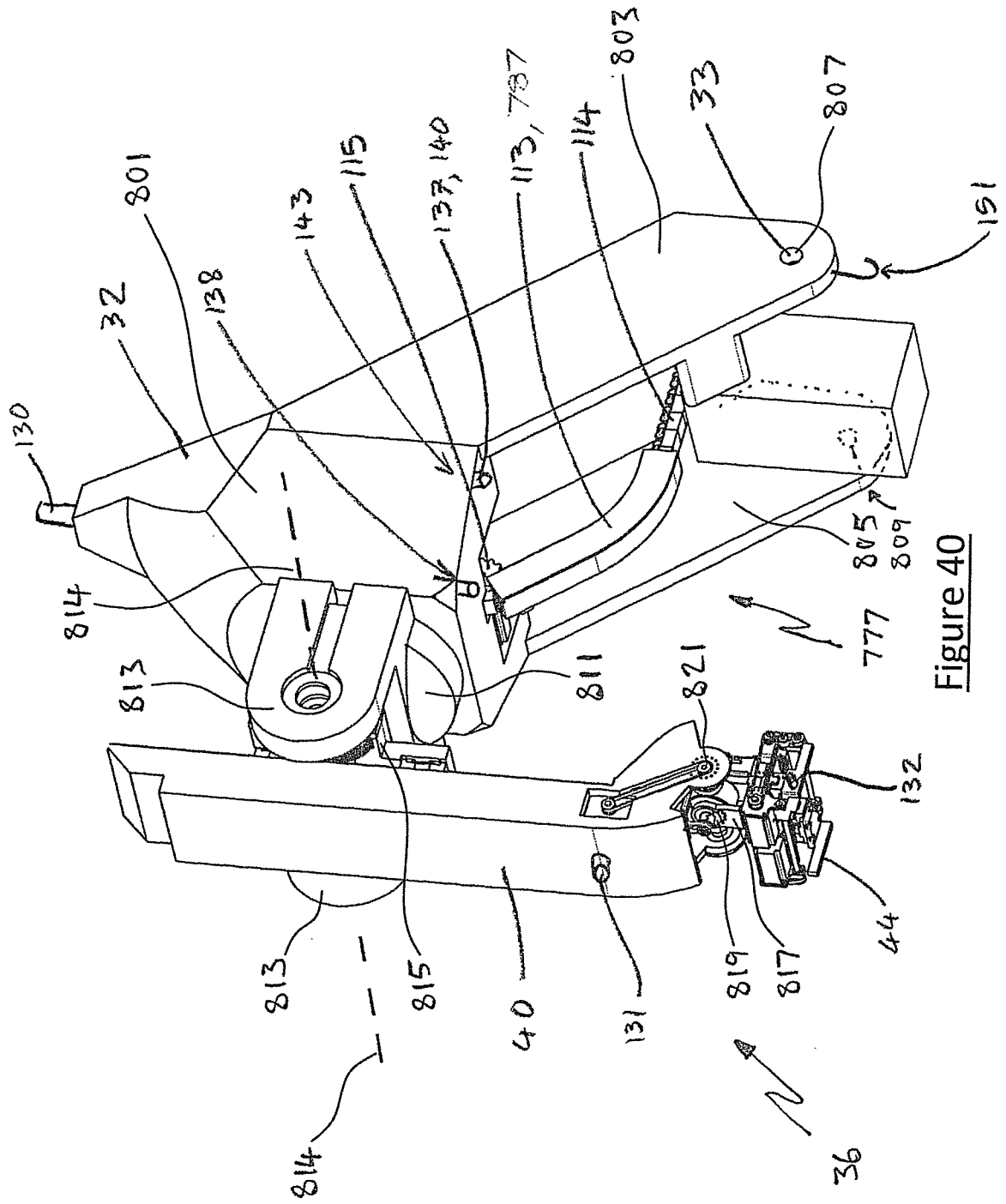


Figure 40

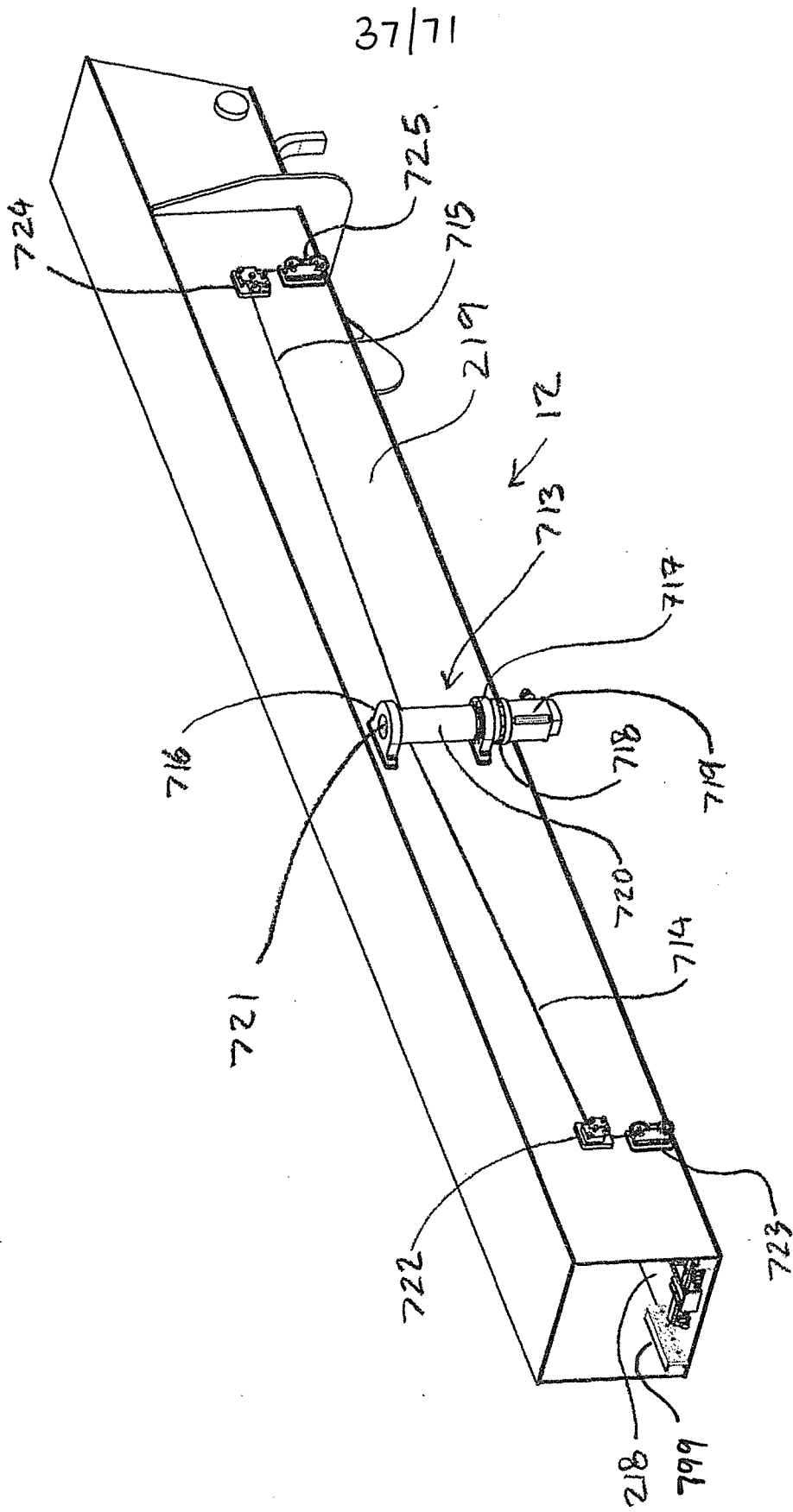


Figure 41

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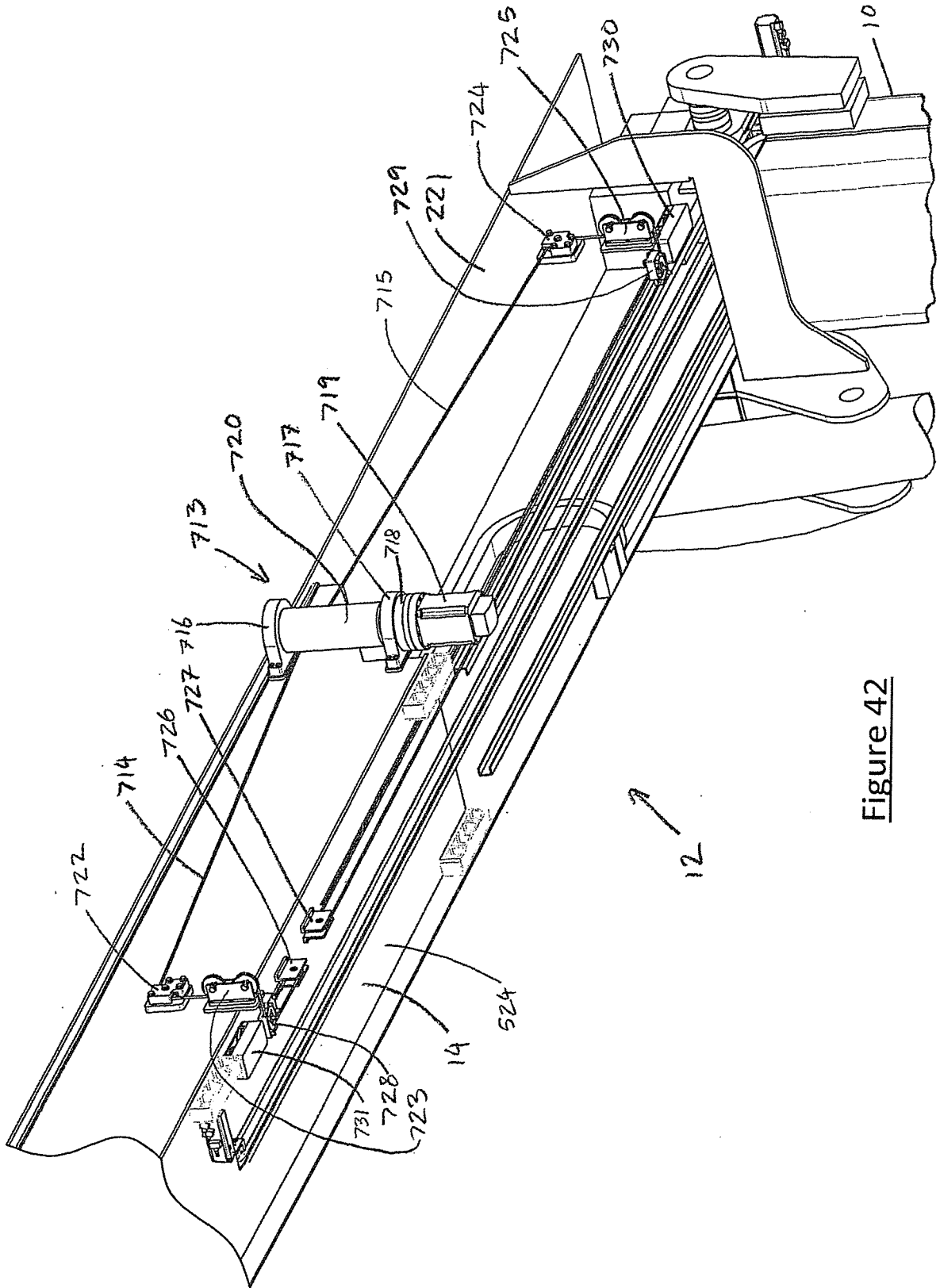


Figure 42

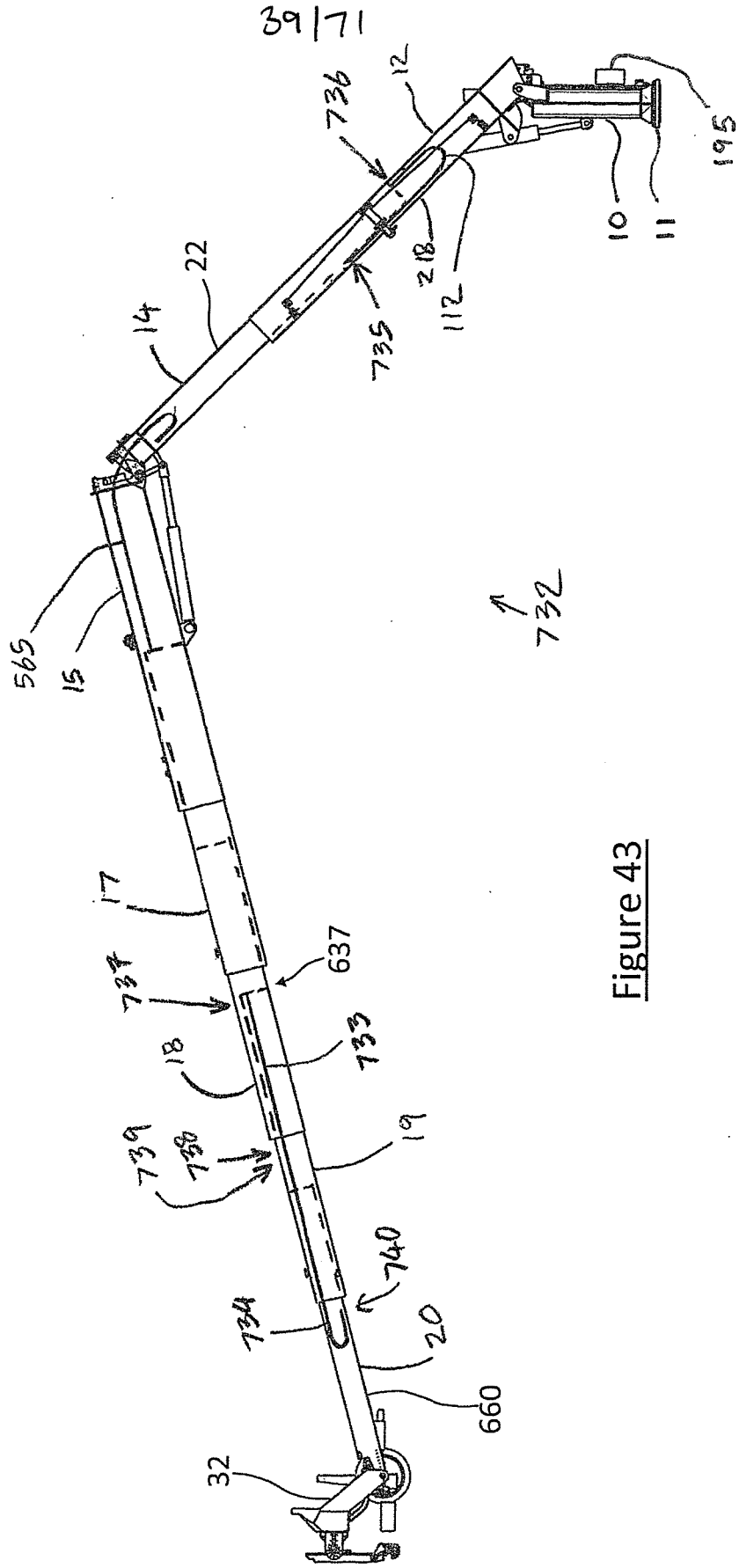


Figure 43

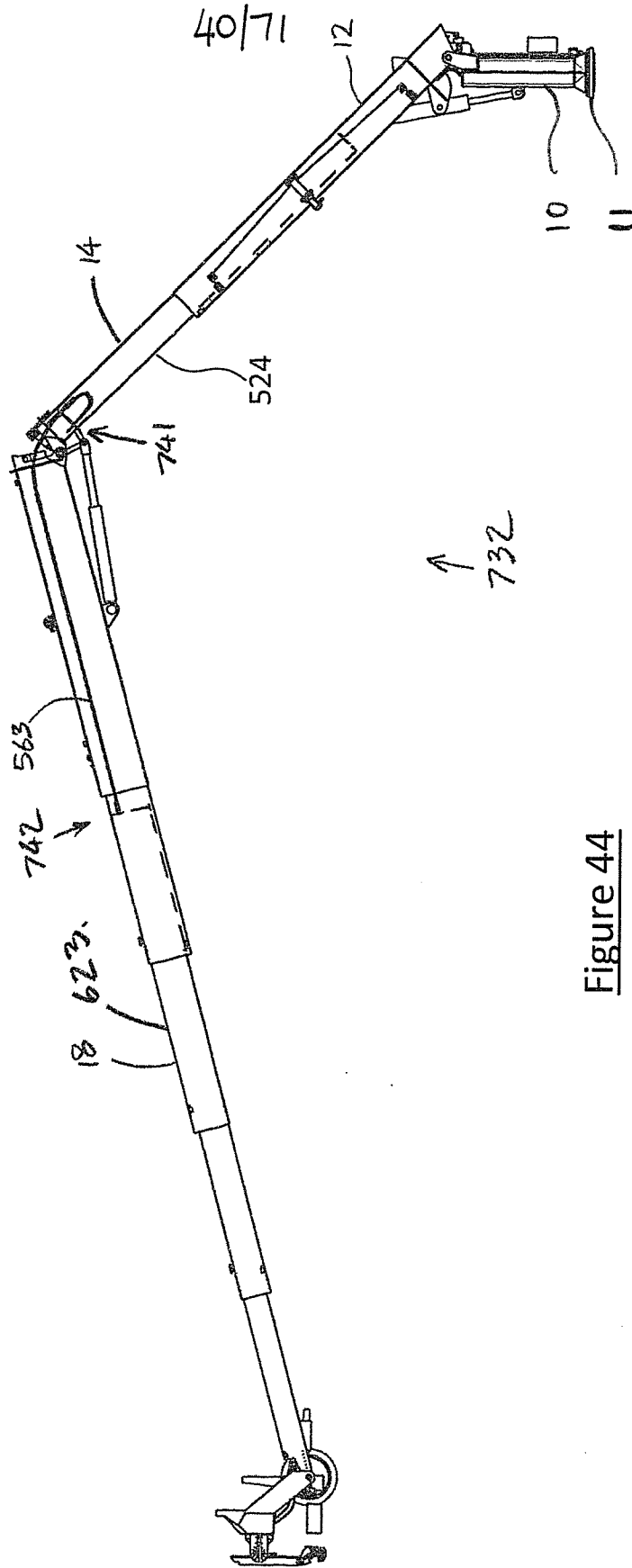


Figure 44

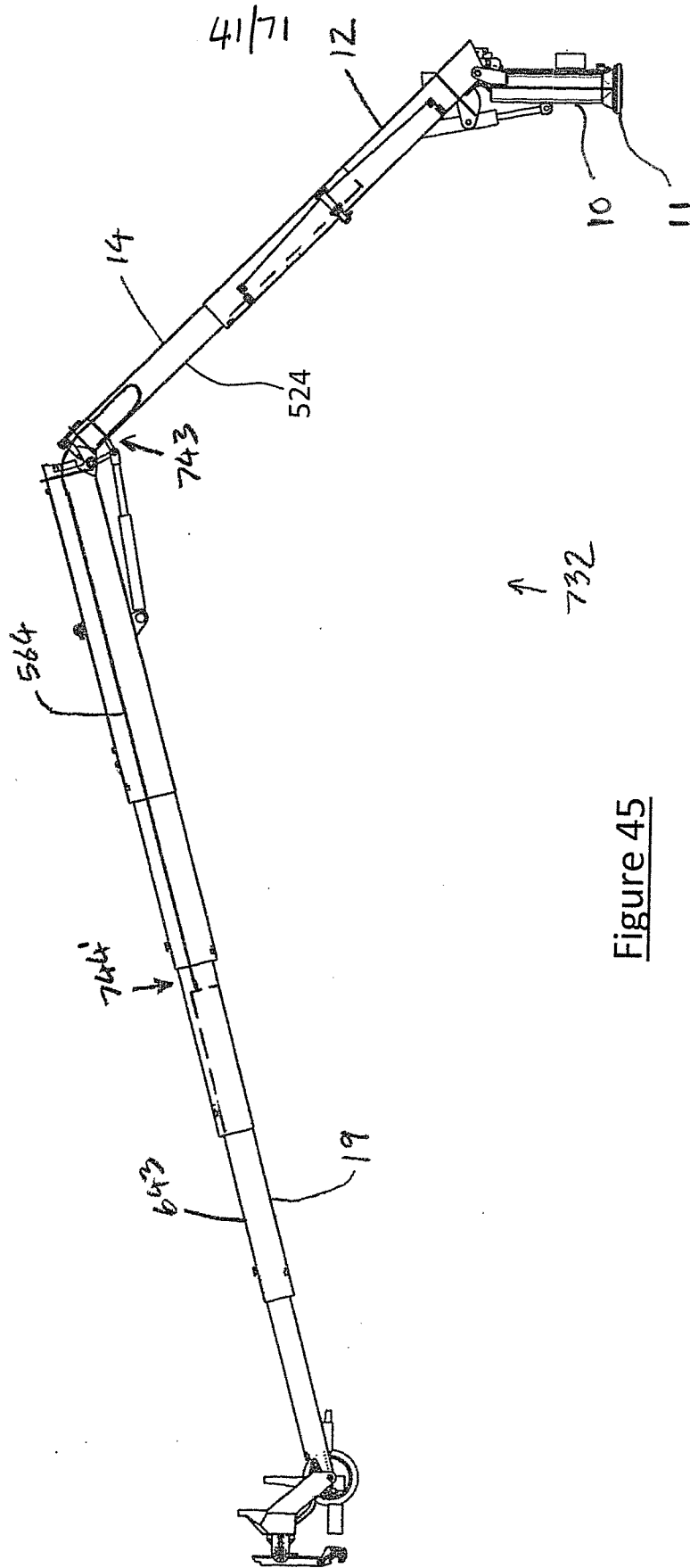


Figure 45

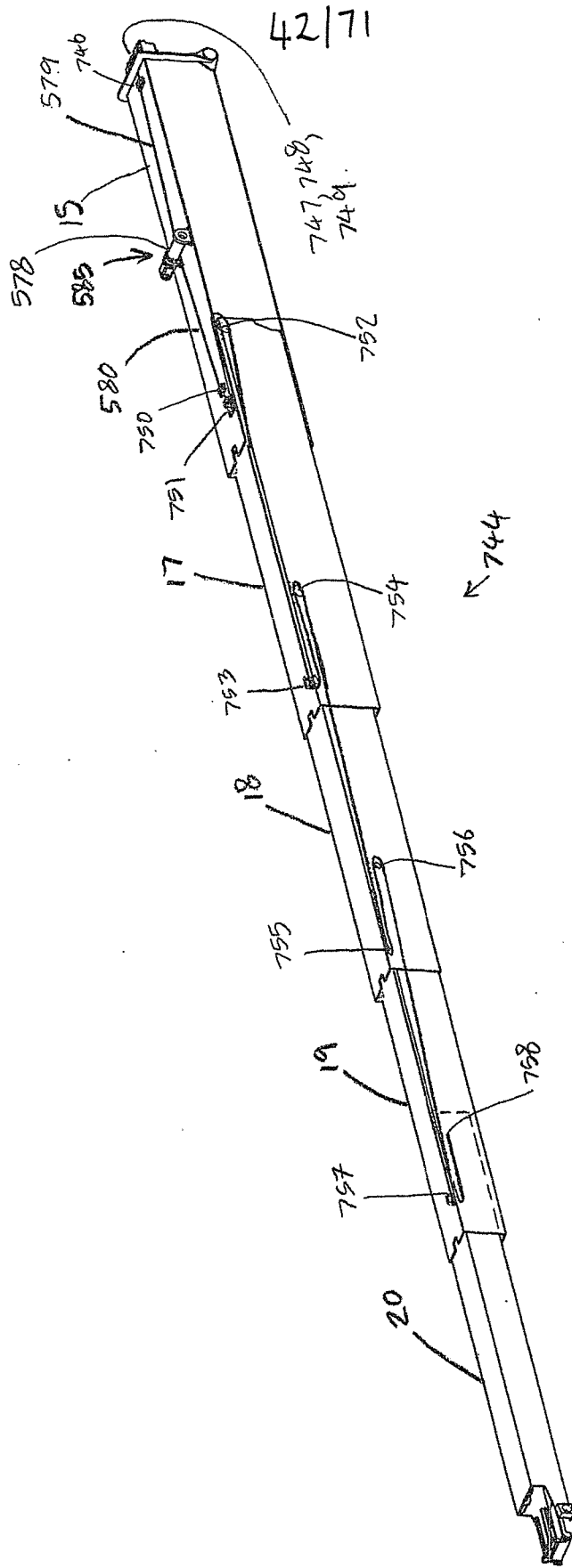


Figure 46

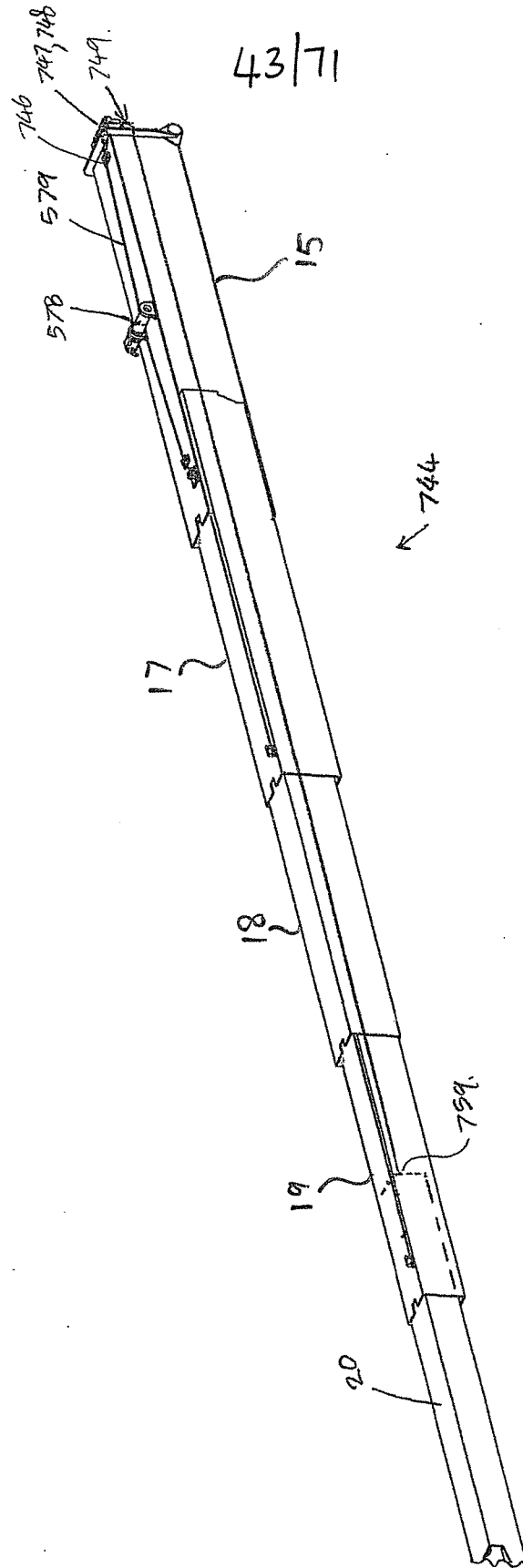


Figure 47

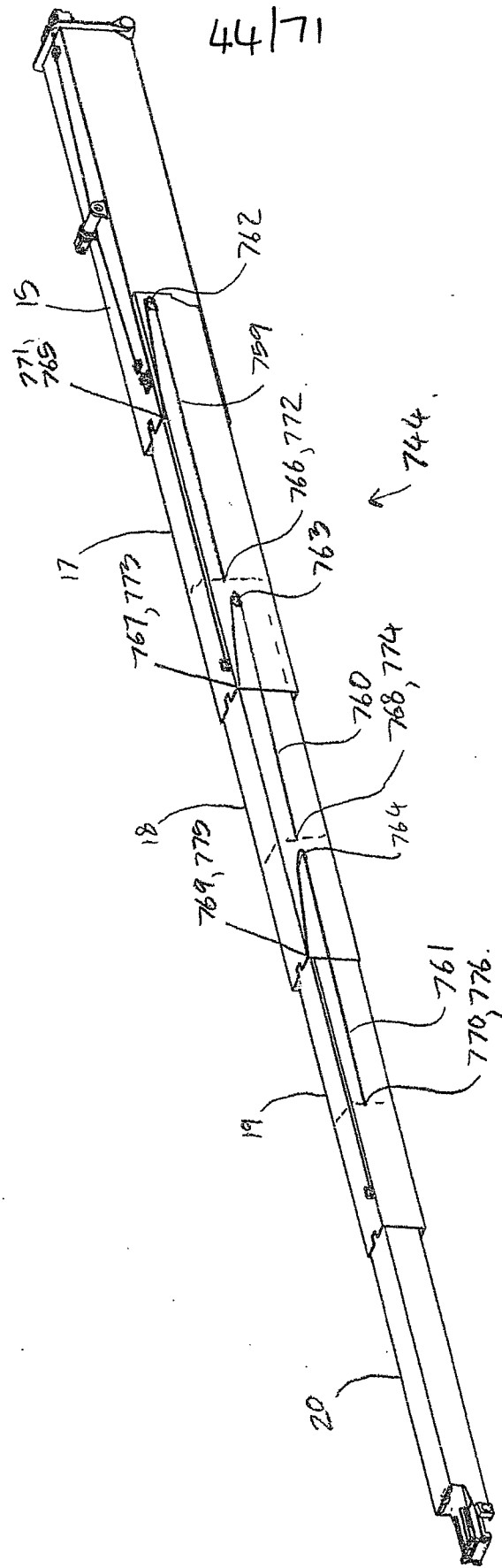
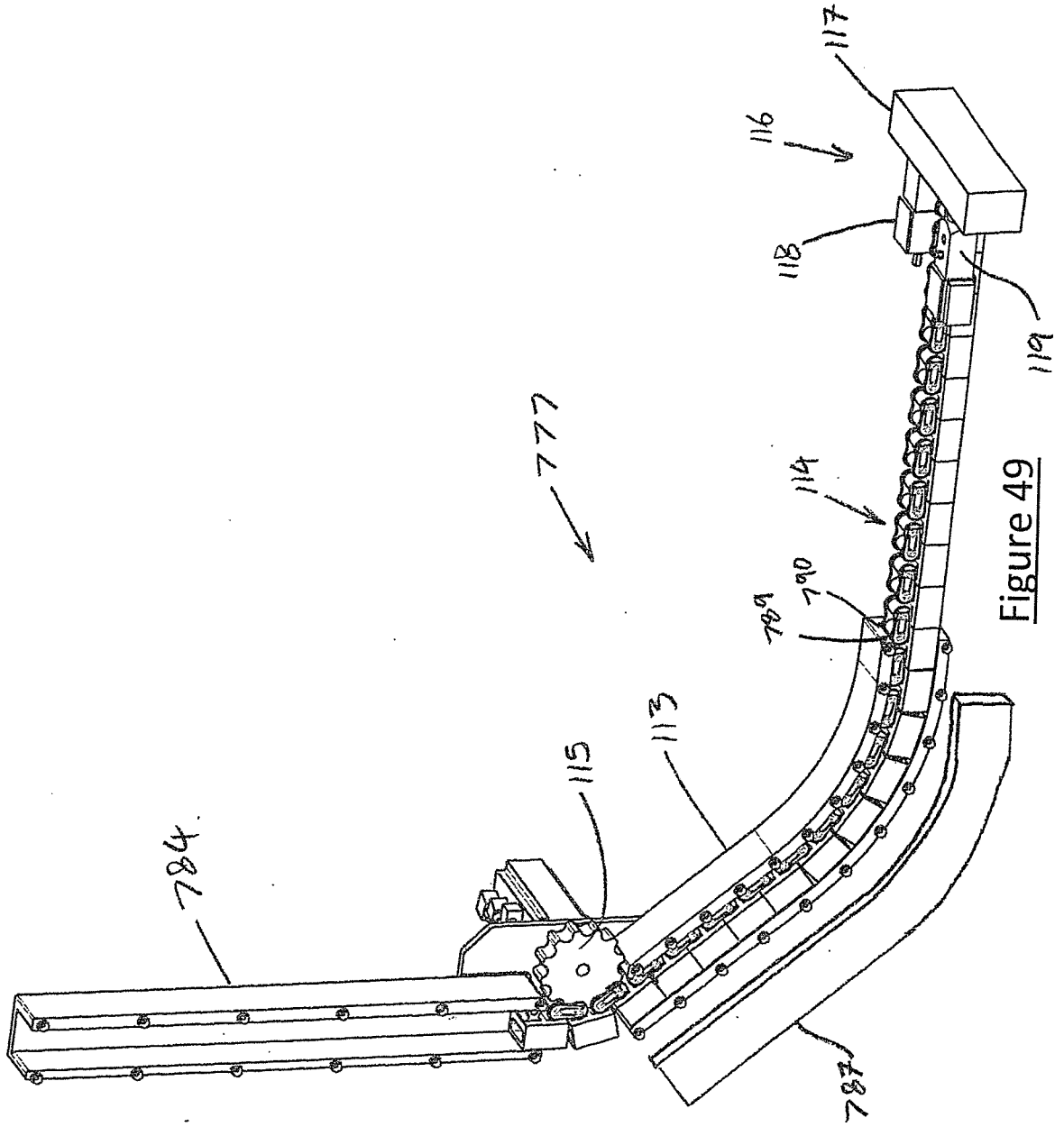


Figure 48

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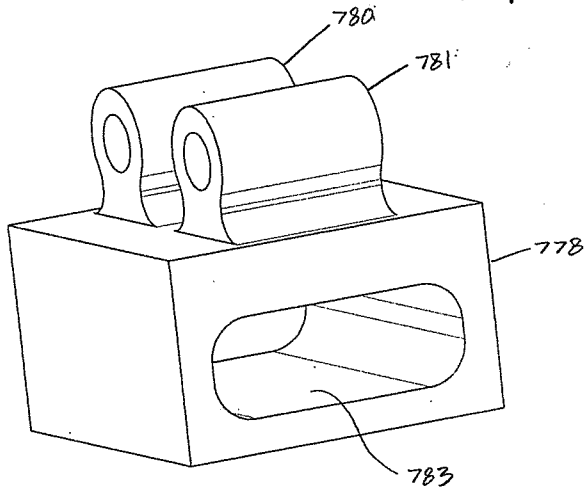


Figure 51

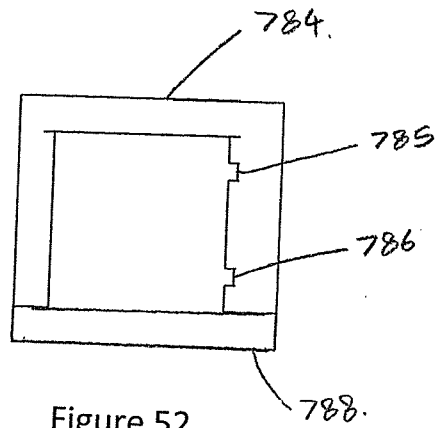


Figure 52

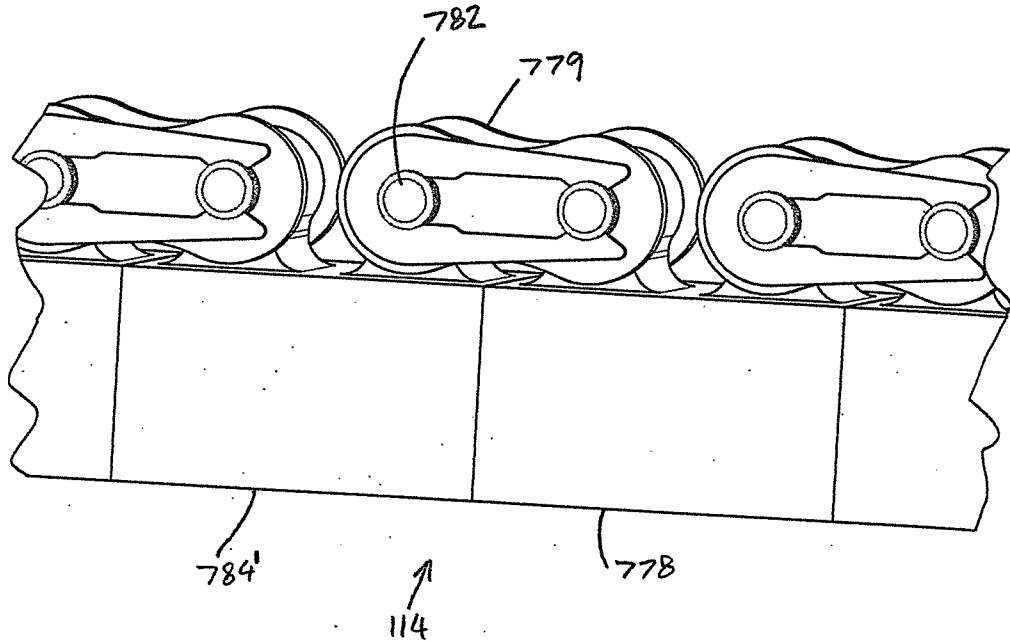


Figure 50

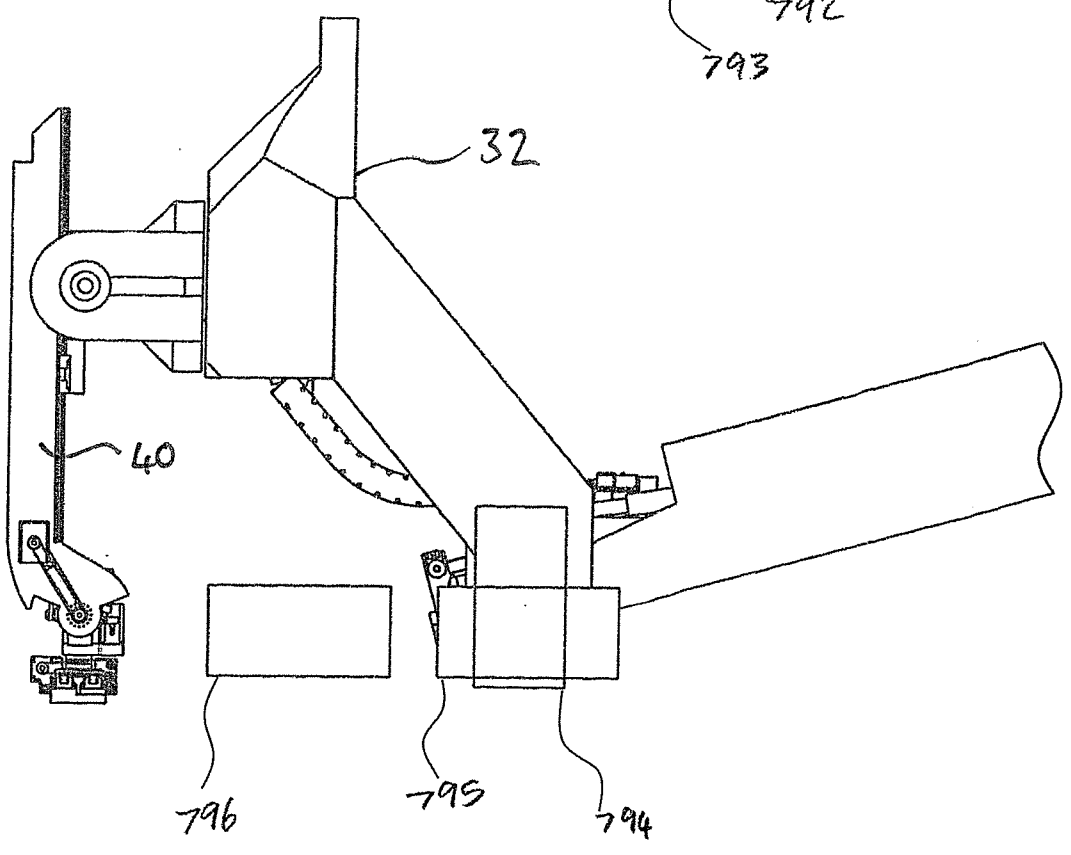
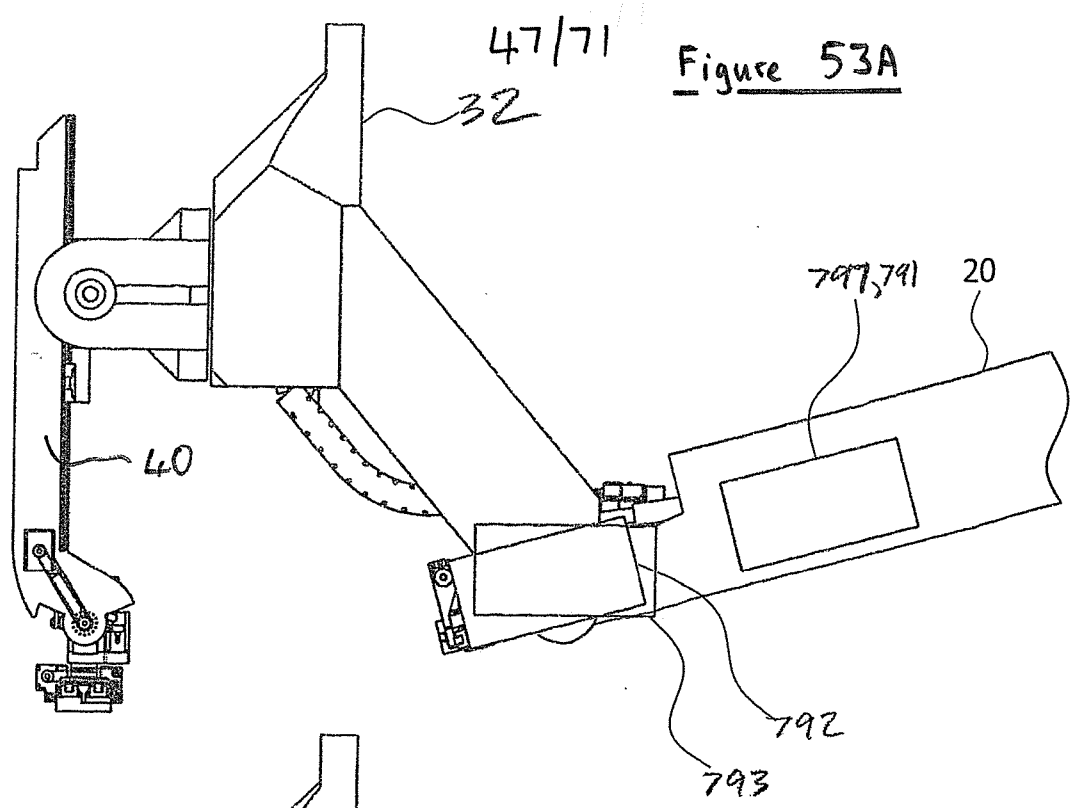


Figure 53

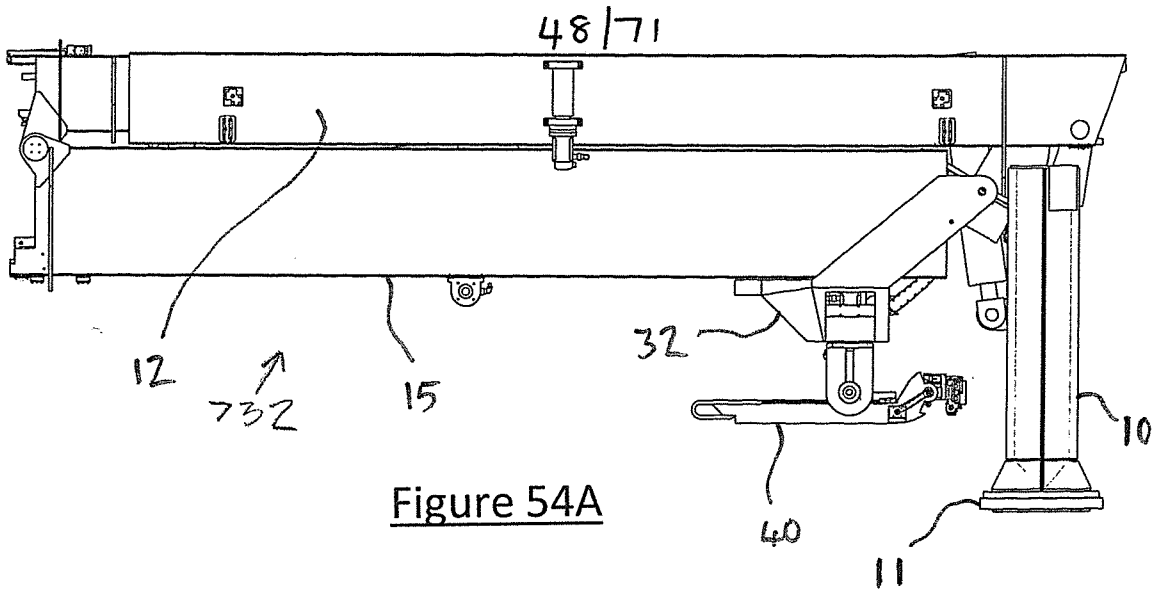


Figure 54A

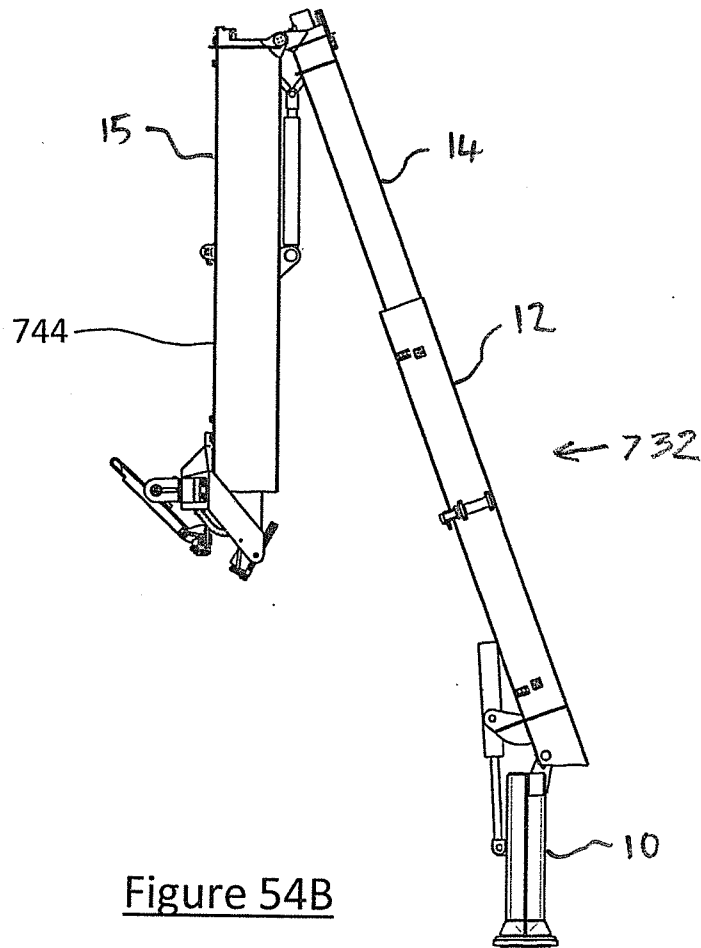


Figure 54B

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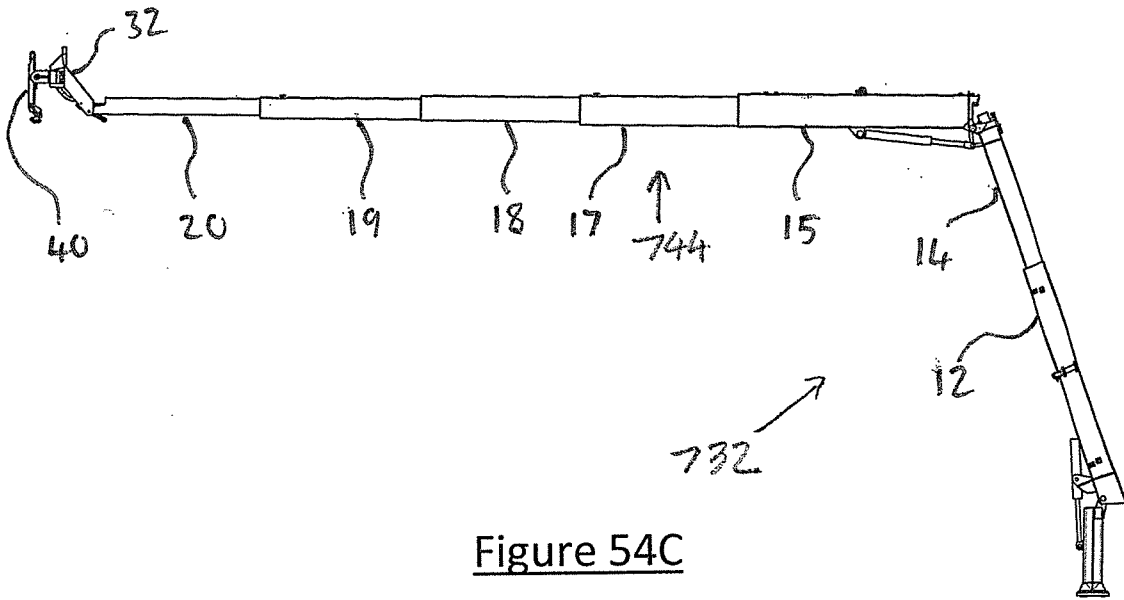


Figure 54C

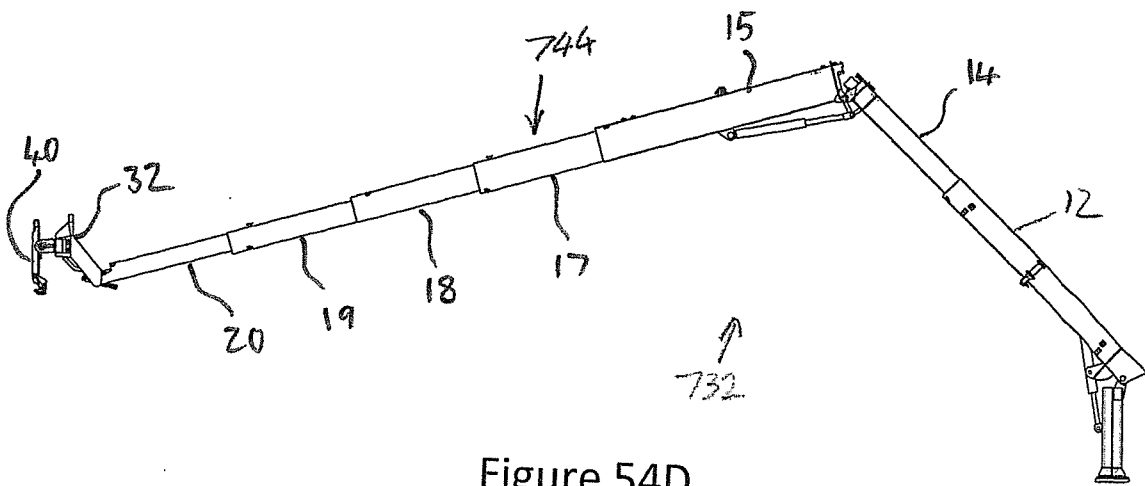


Figure 54D

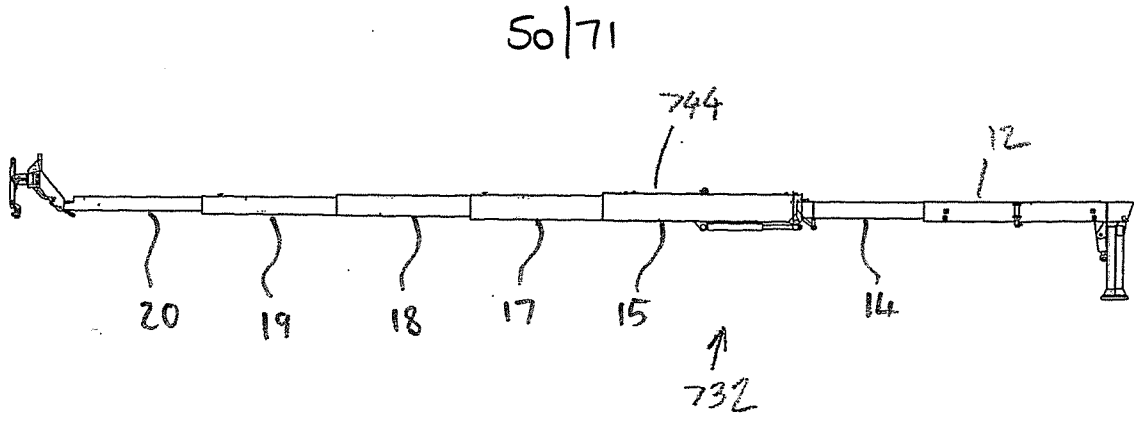


Figure 54E

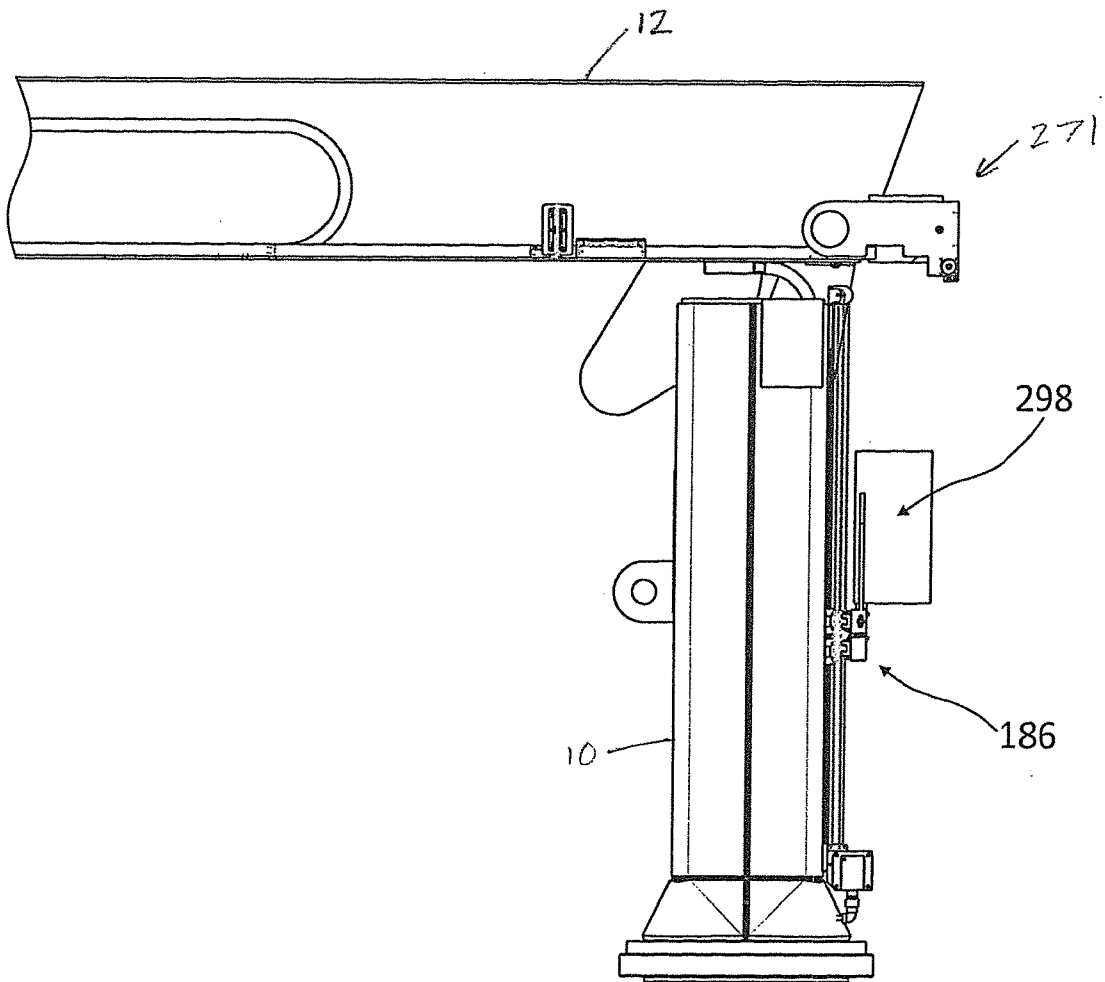


Figure 55A

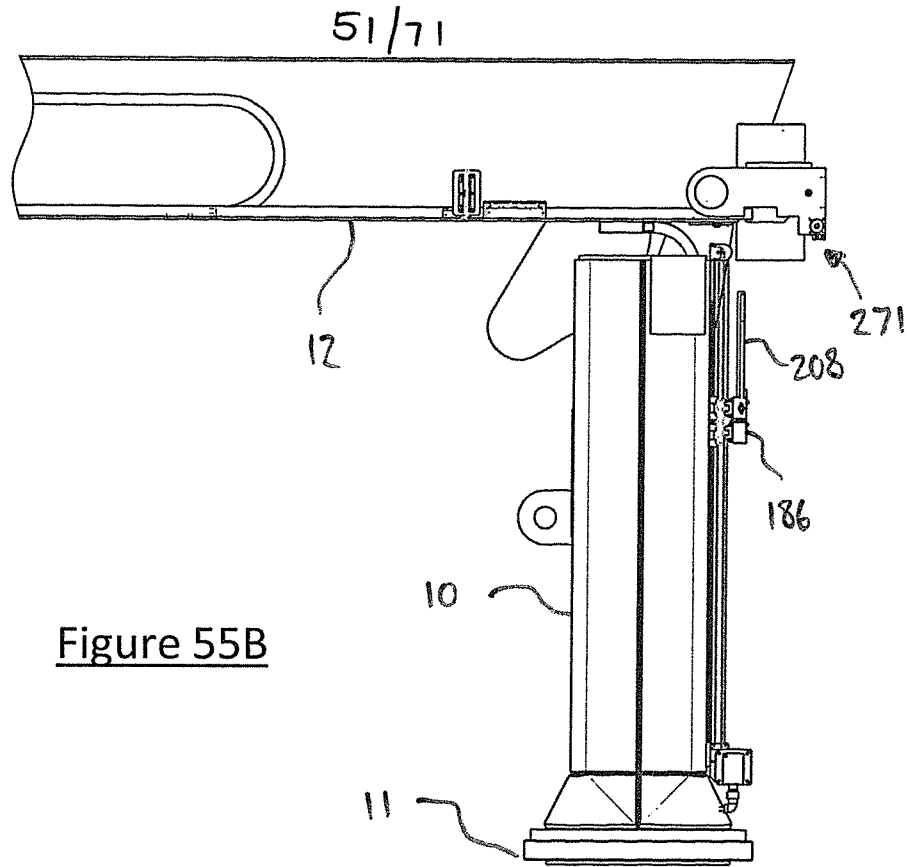


Figure 55B

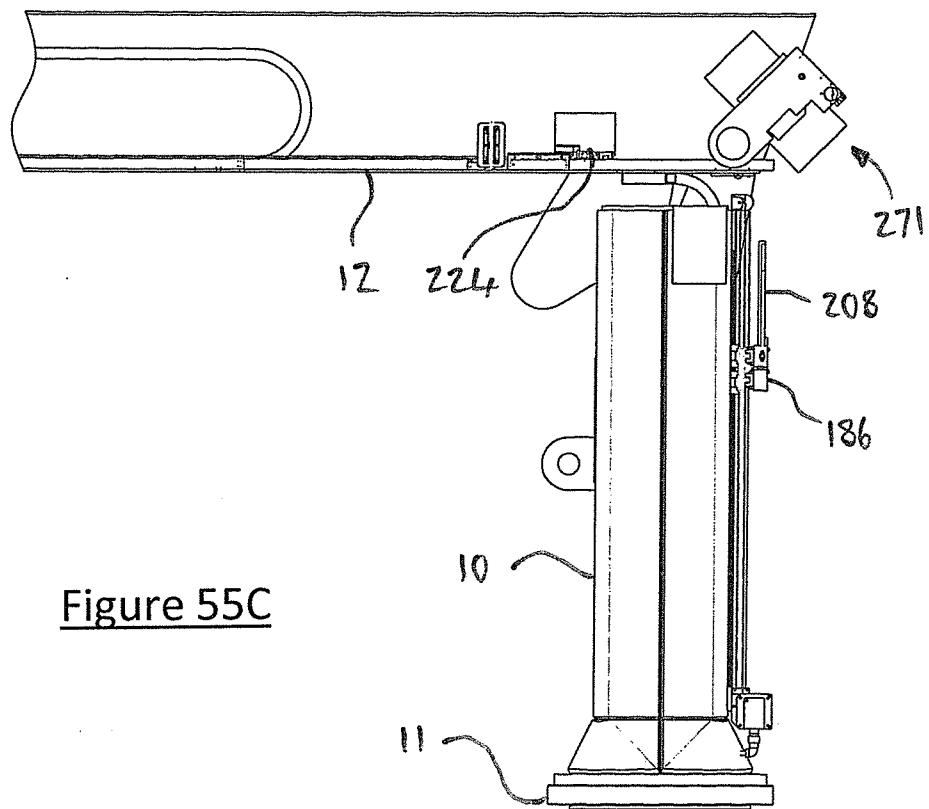


Figure 55C

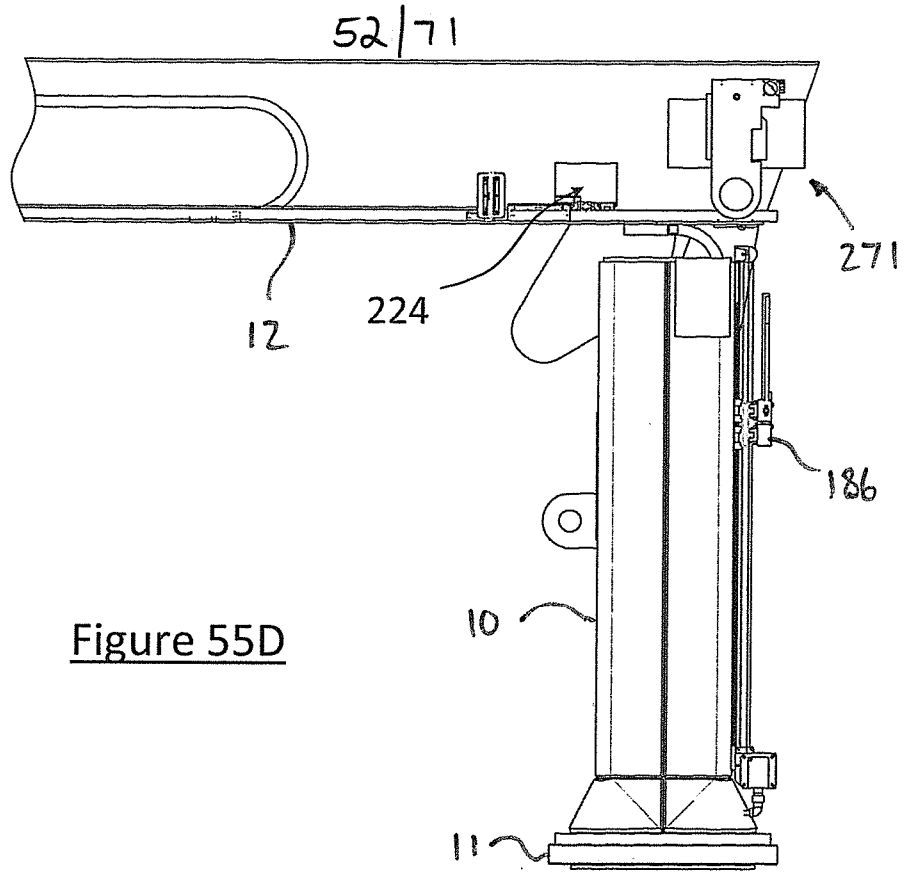


Figure 55D

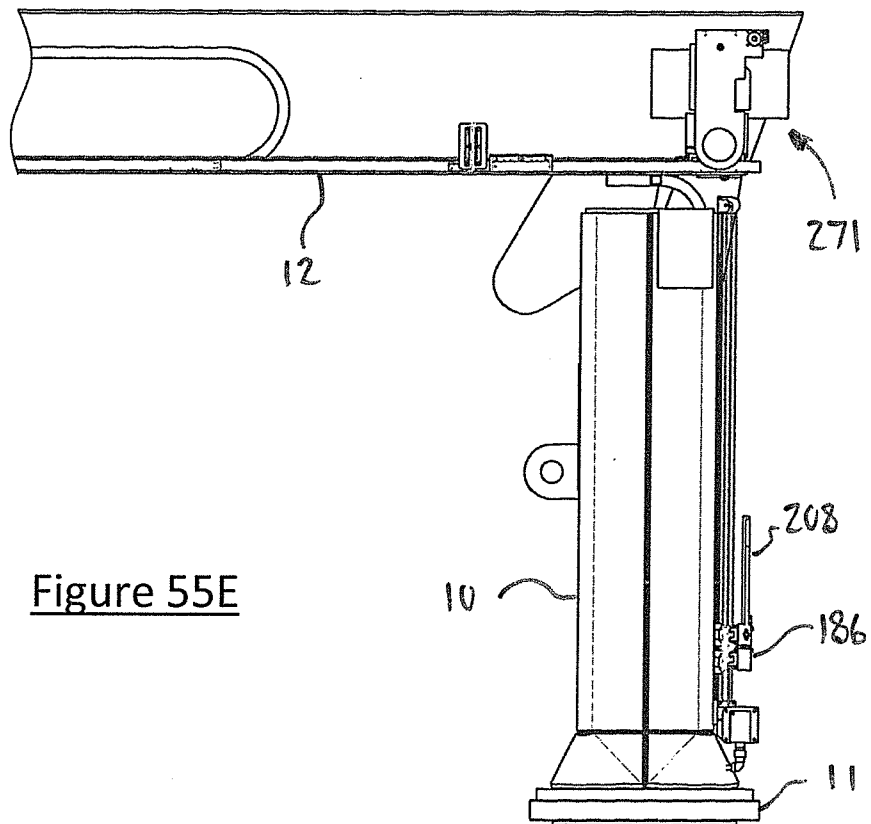


Figure 55E

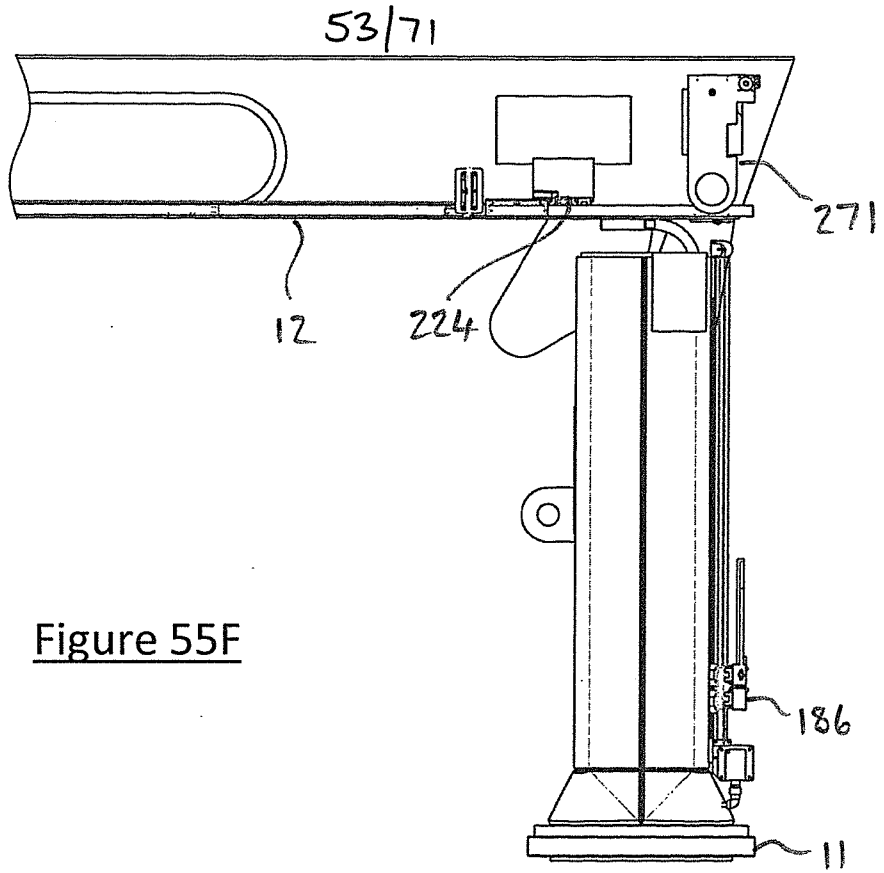


Figure 55F

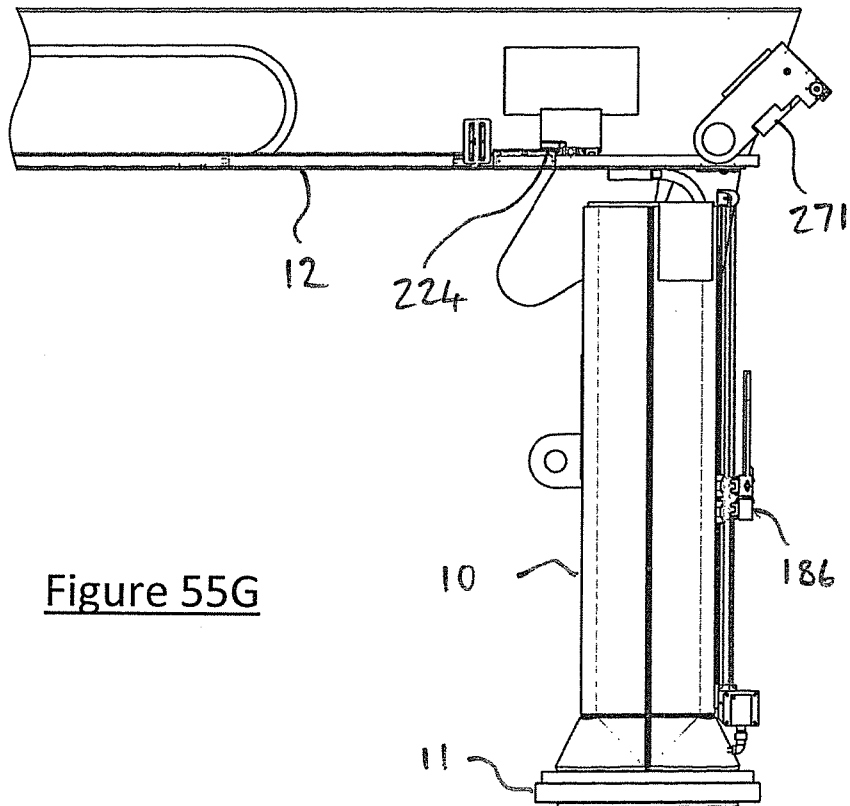


Figure 55G

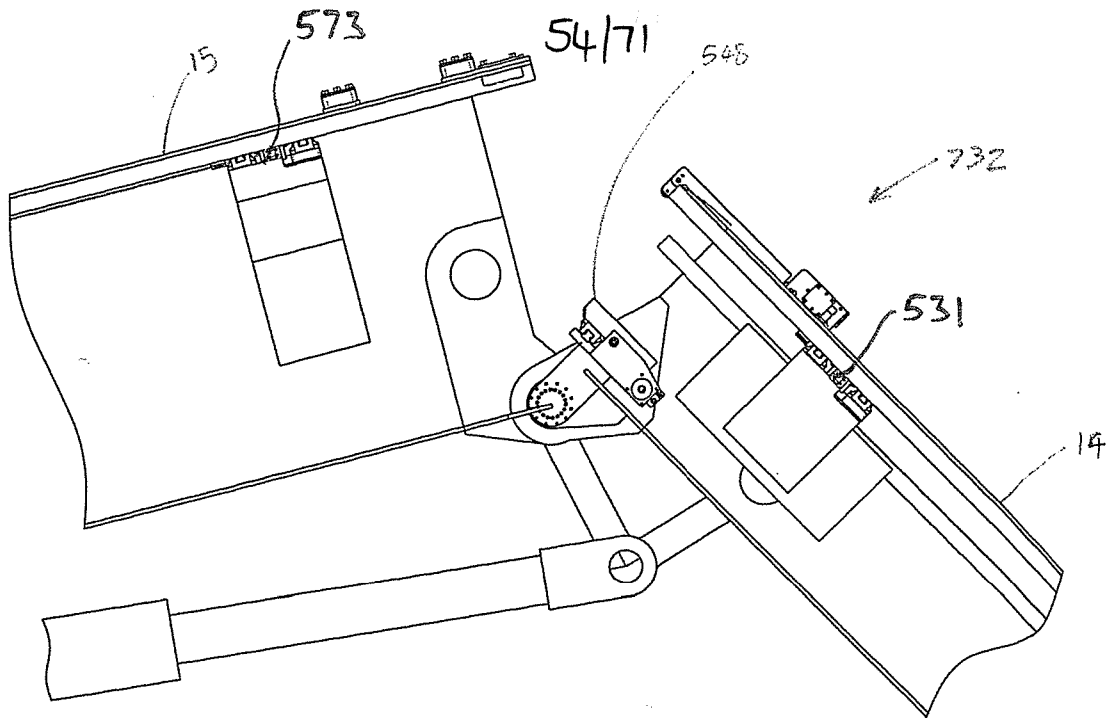


Figure 56A

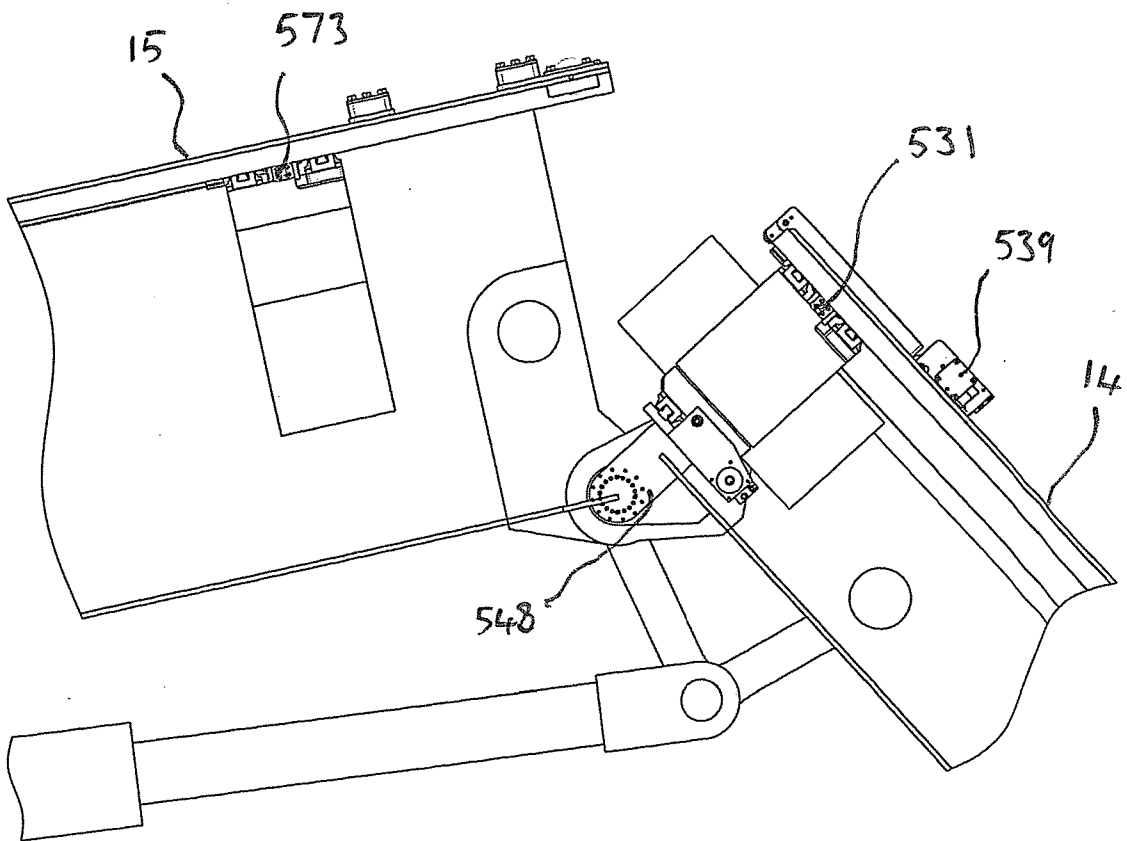
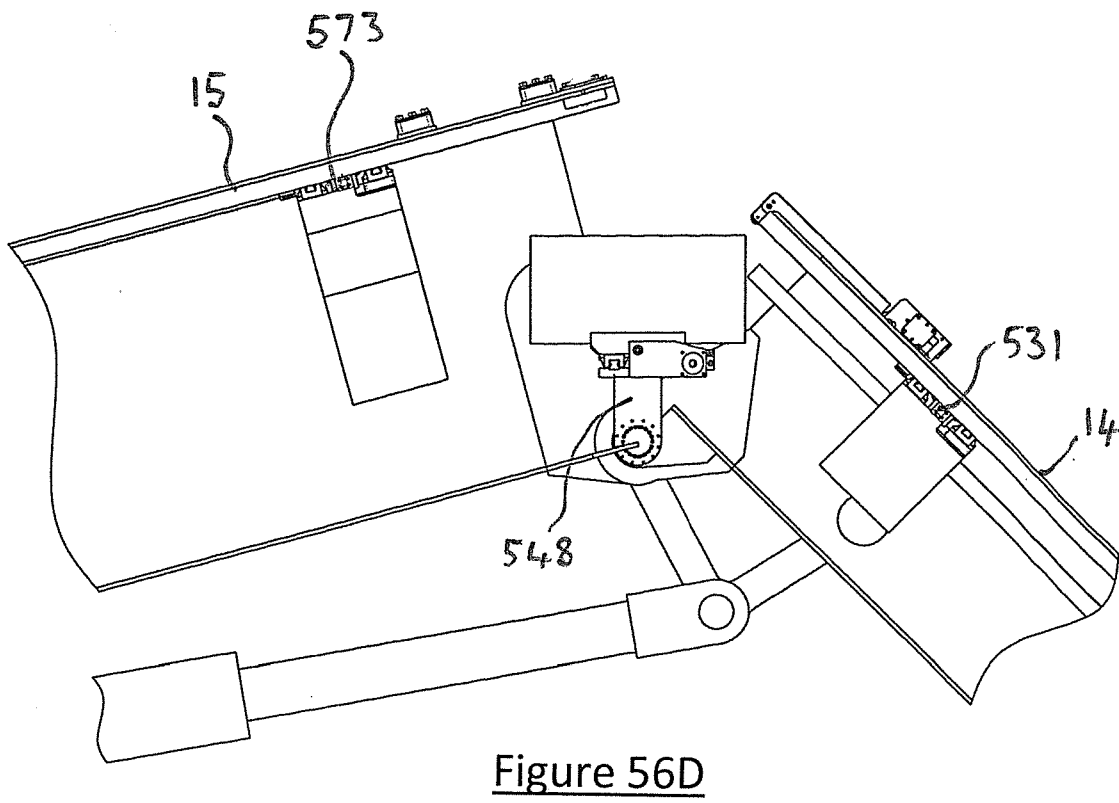
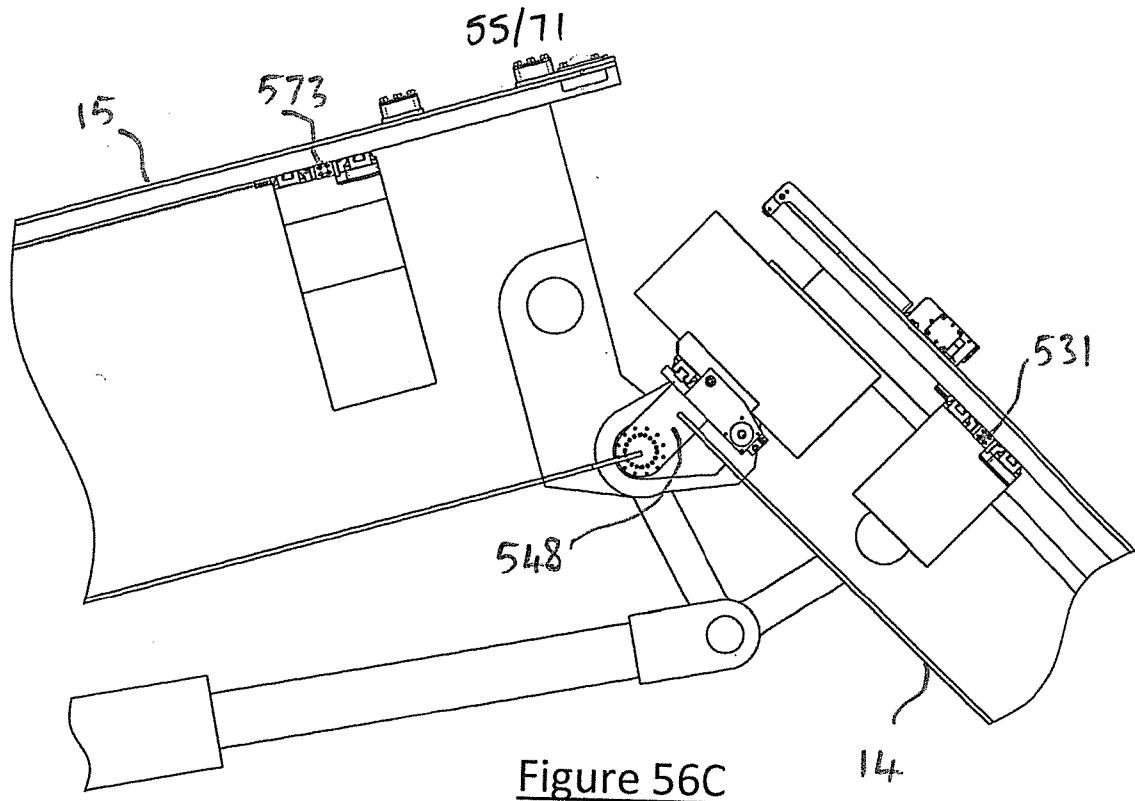


Figure 56B



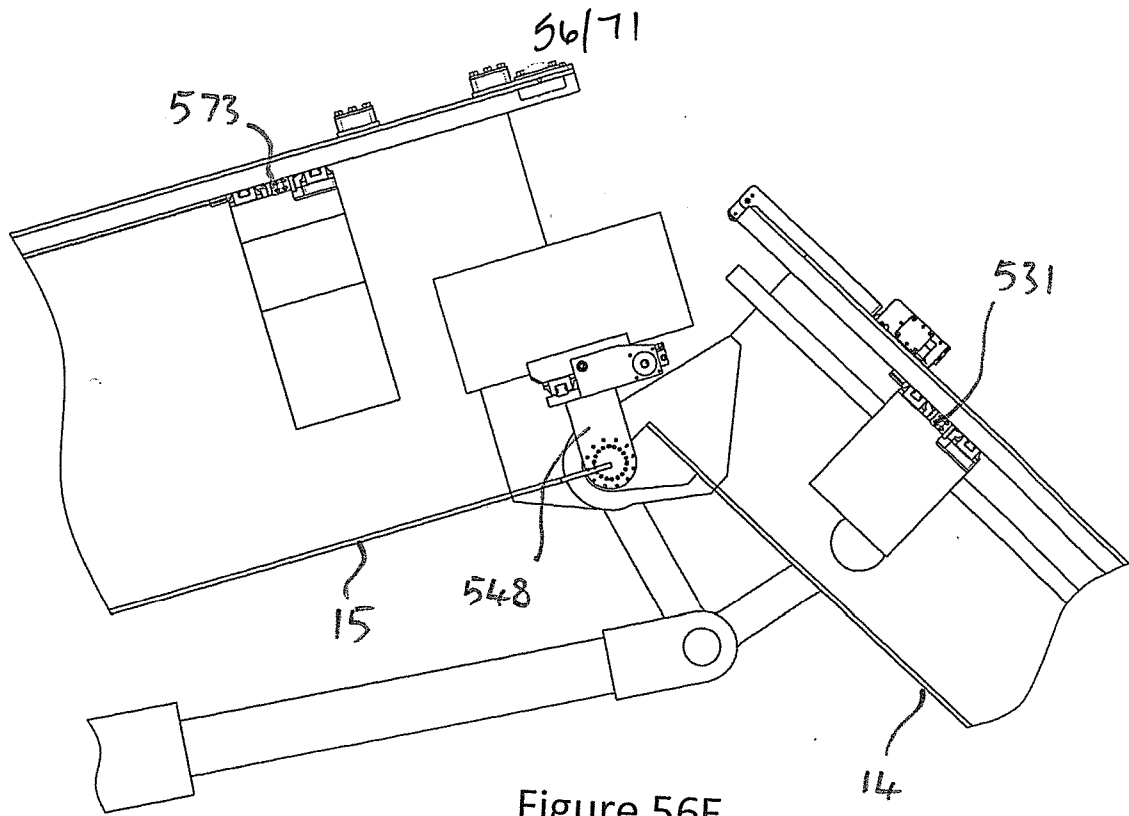


Figure 56E

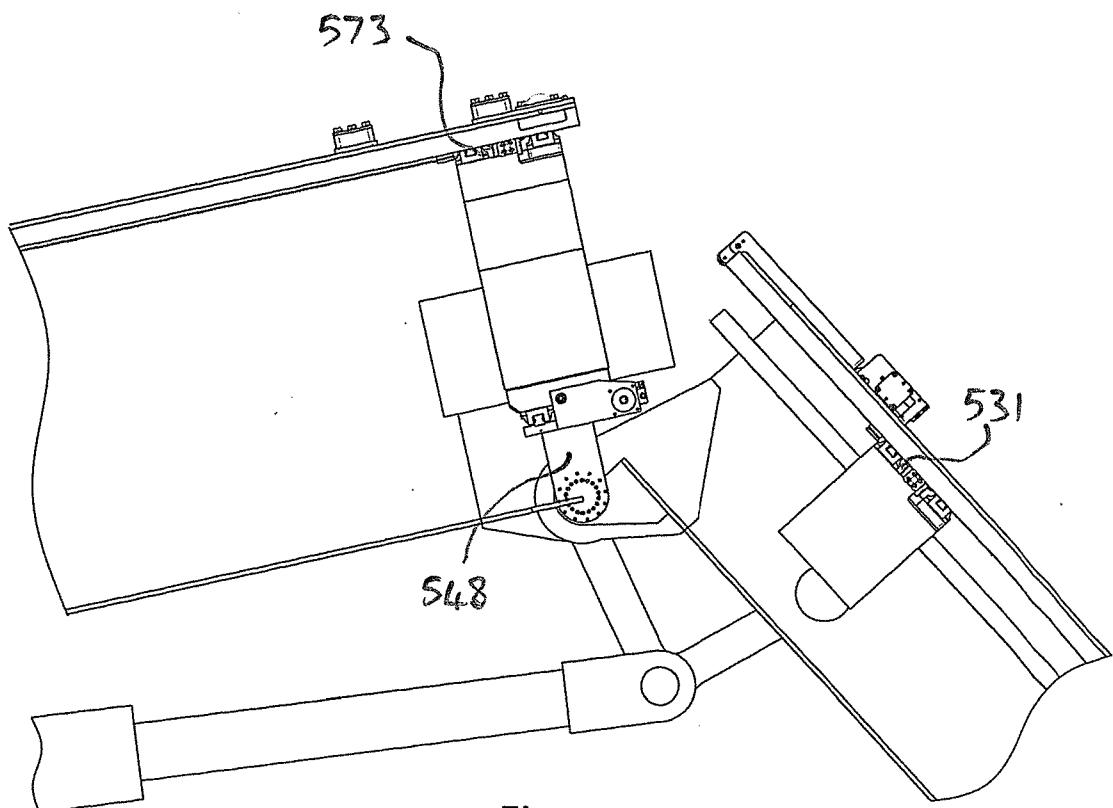


Figure 56F

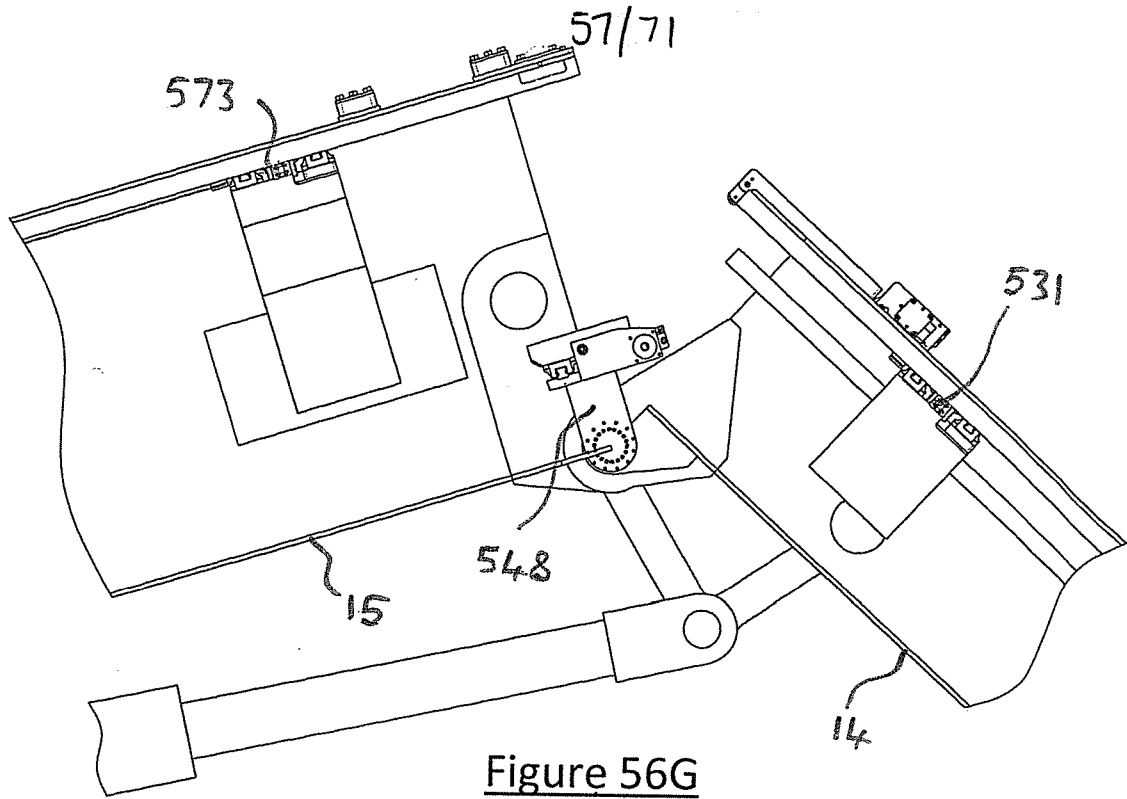


Figure 56G

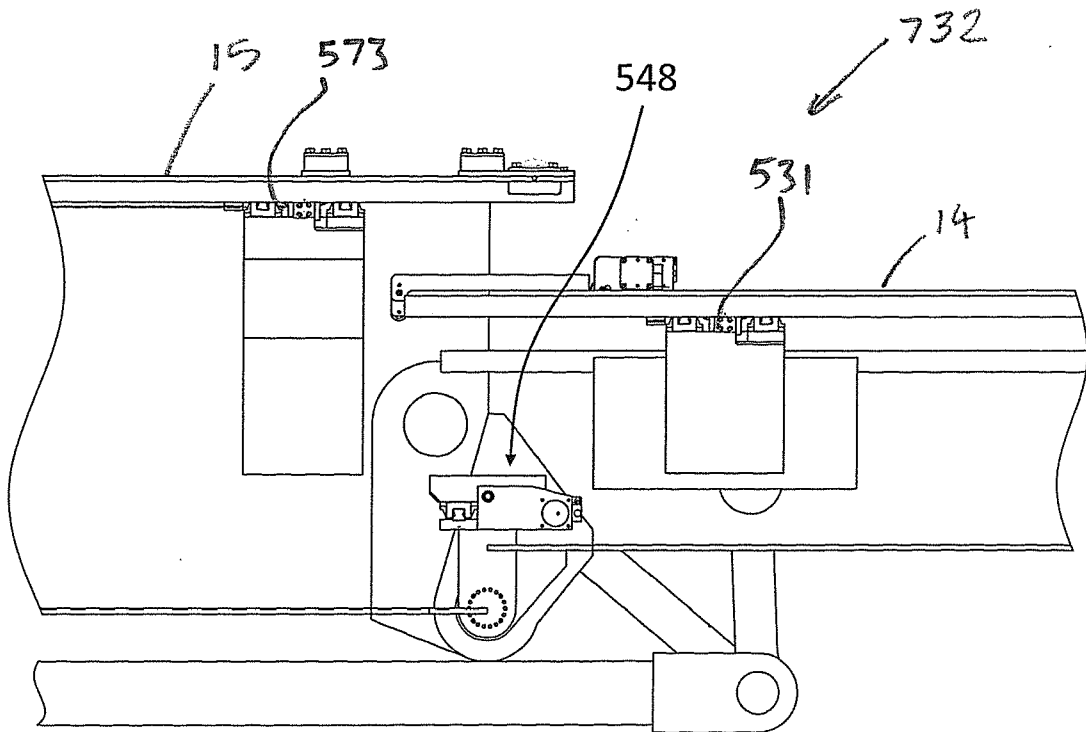
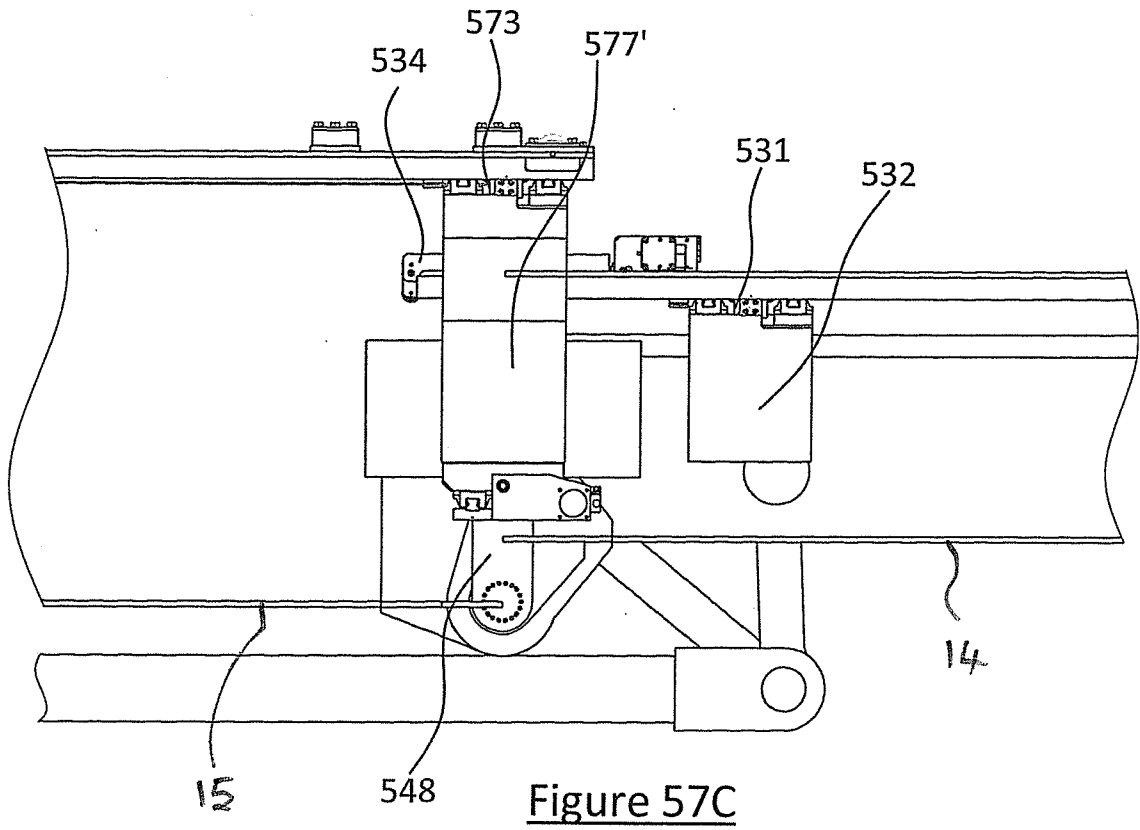
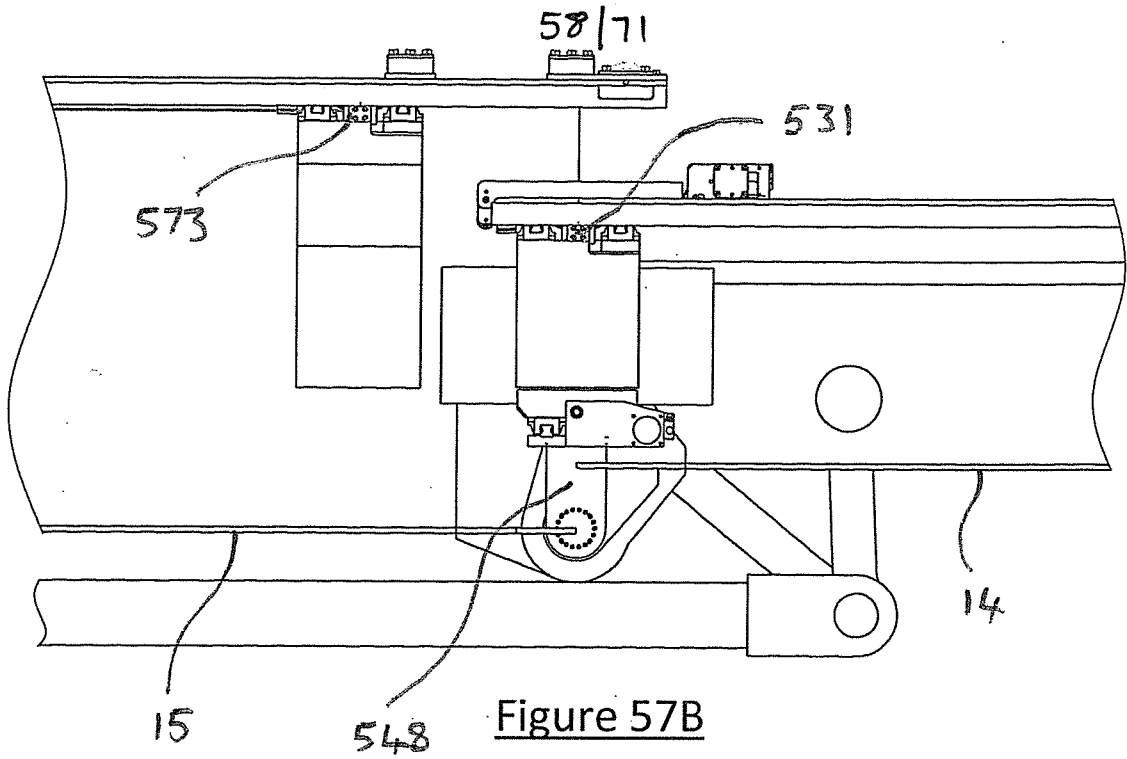


Figure 57A



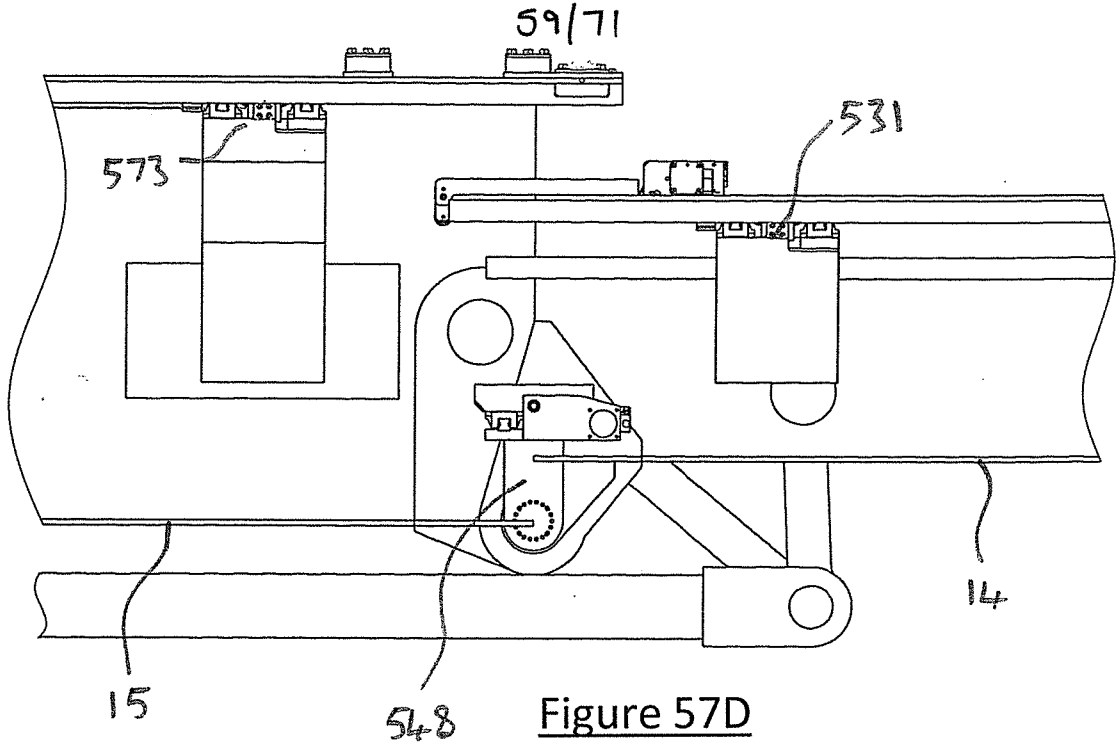


Figure 57D

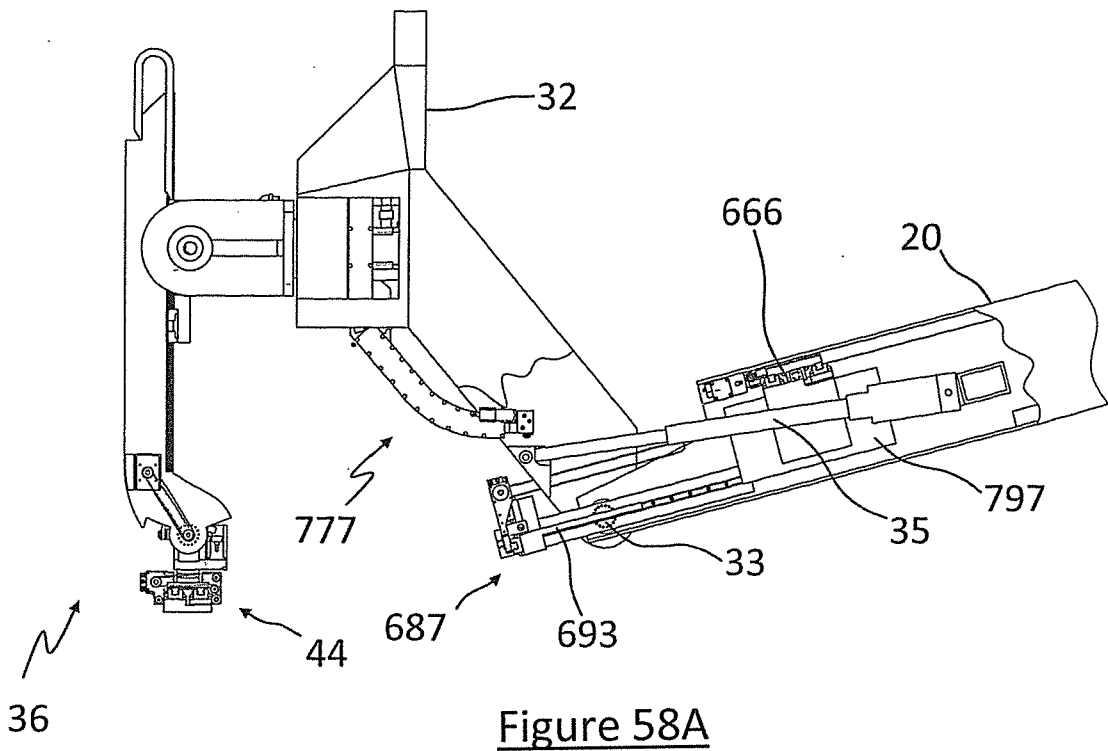


Figure 58A

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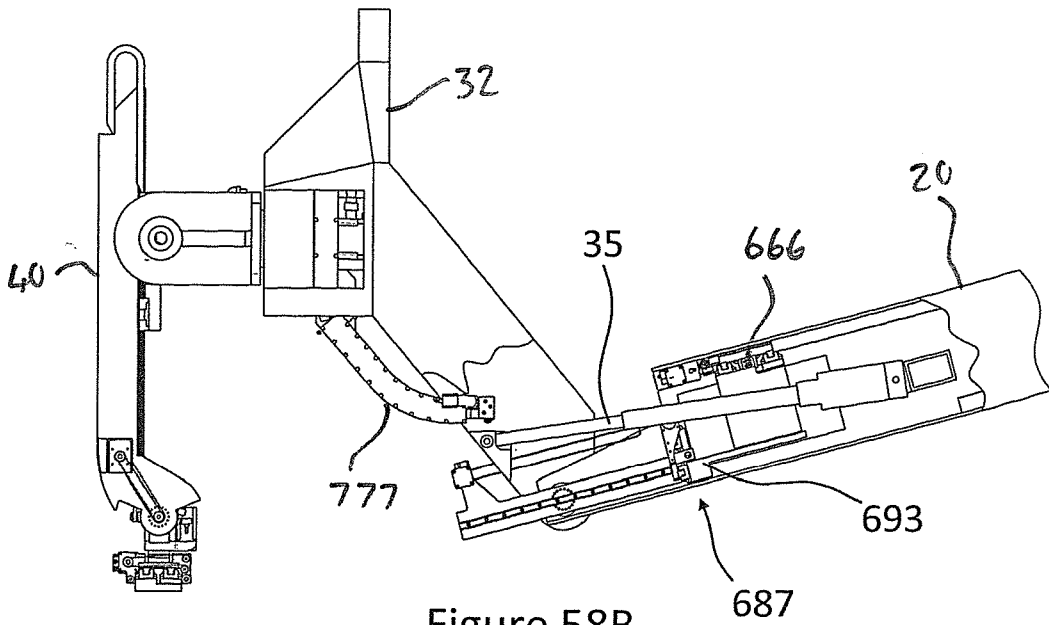


Figure 58B

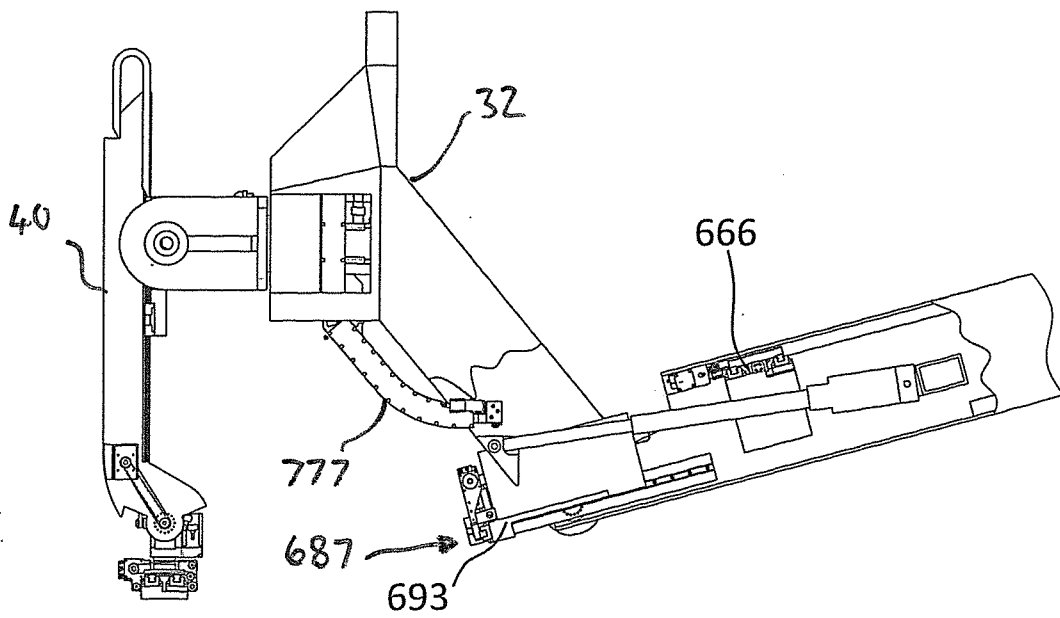
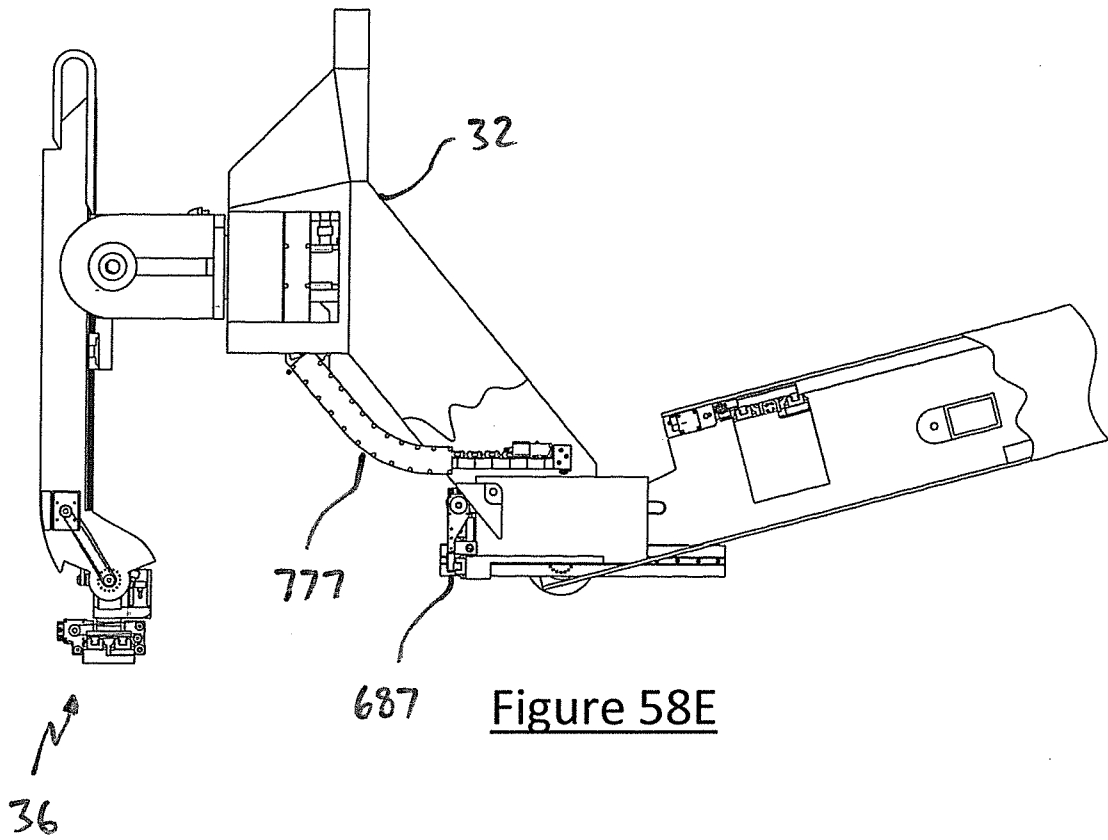
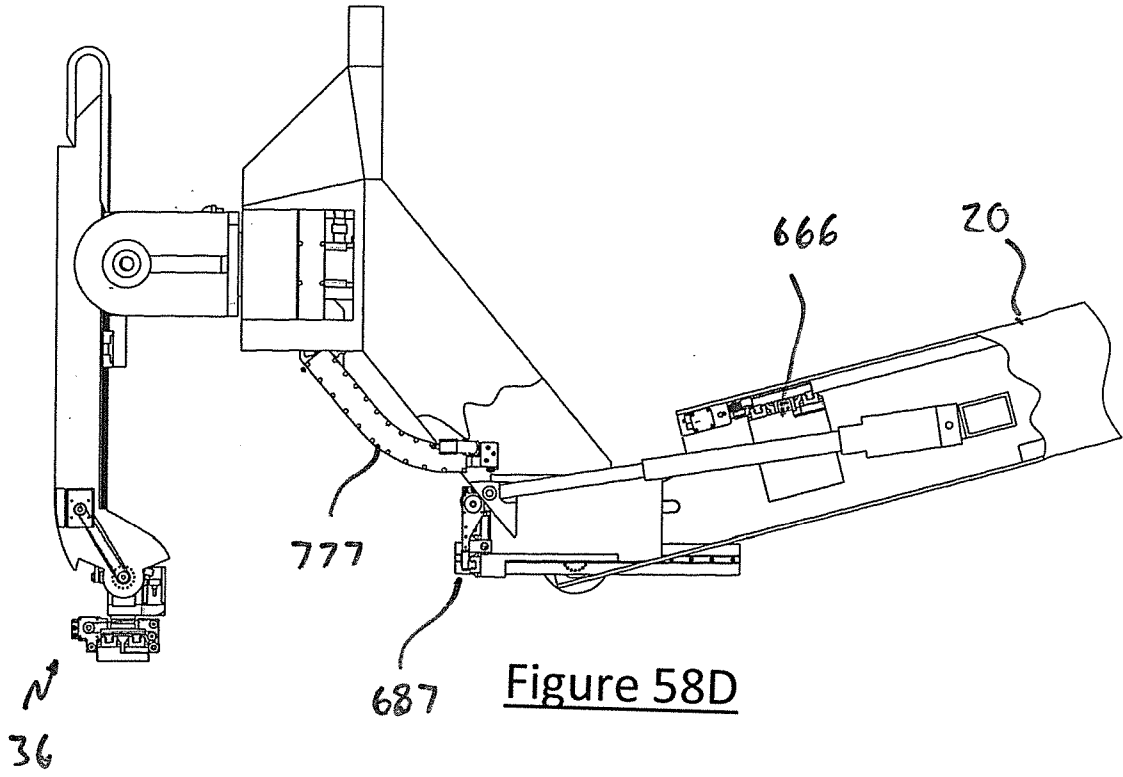


Figure 58C

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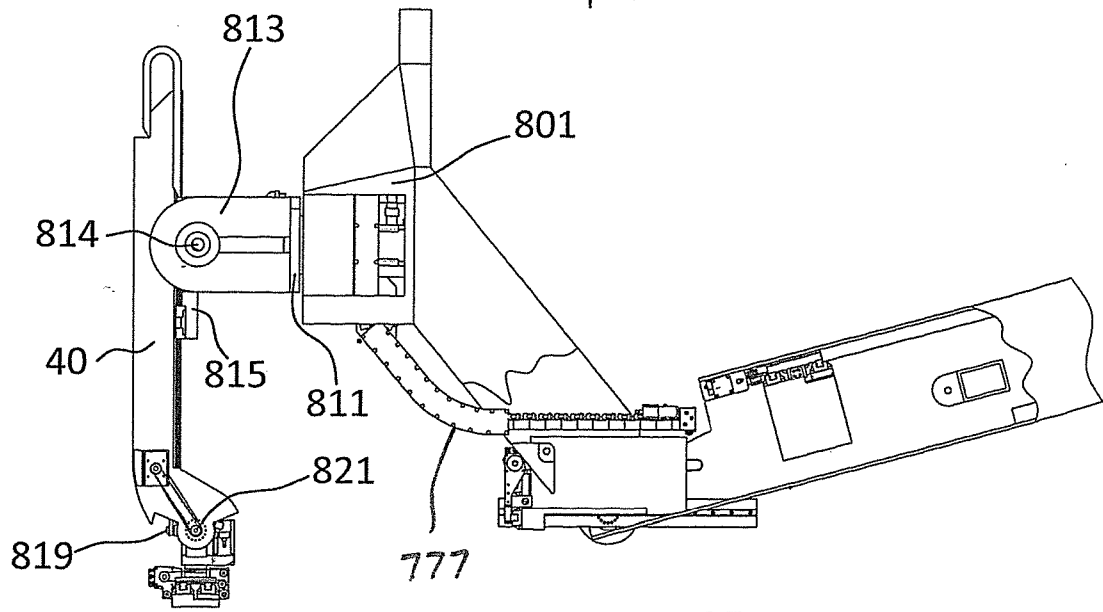


Figure 58F

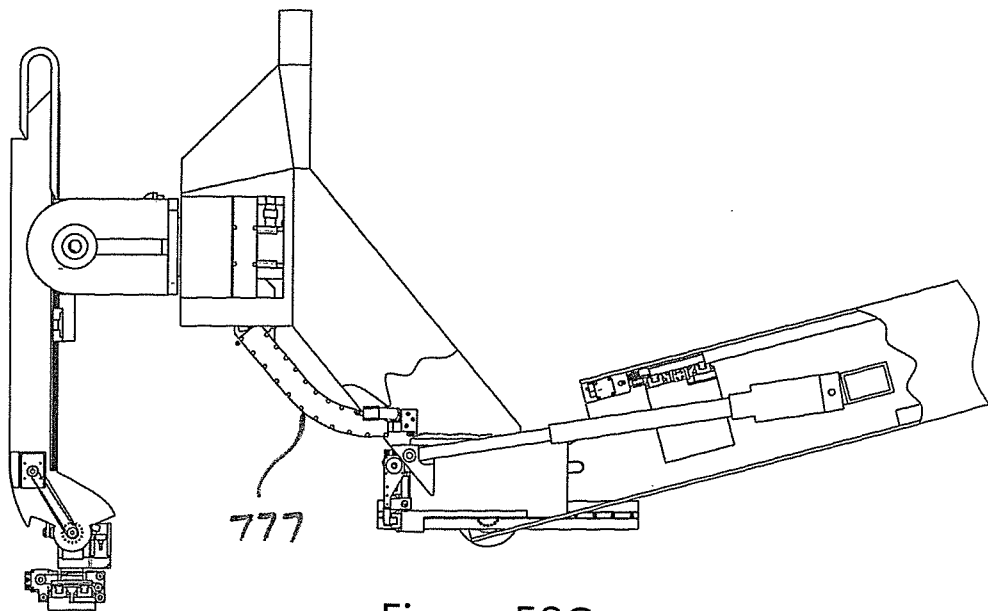
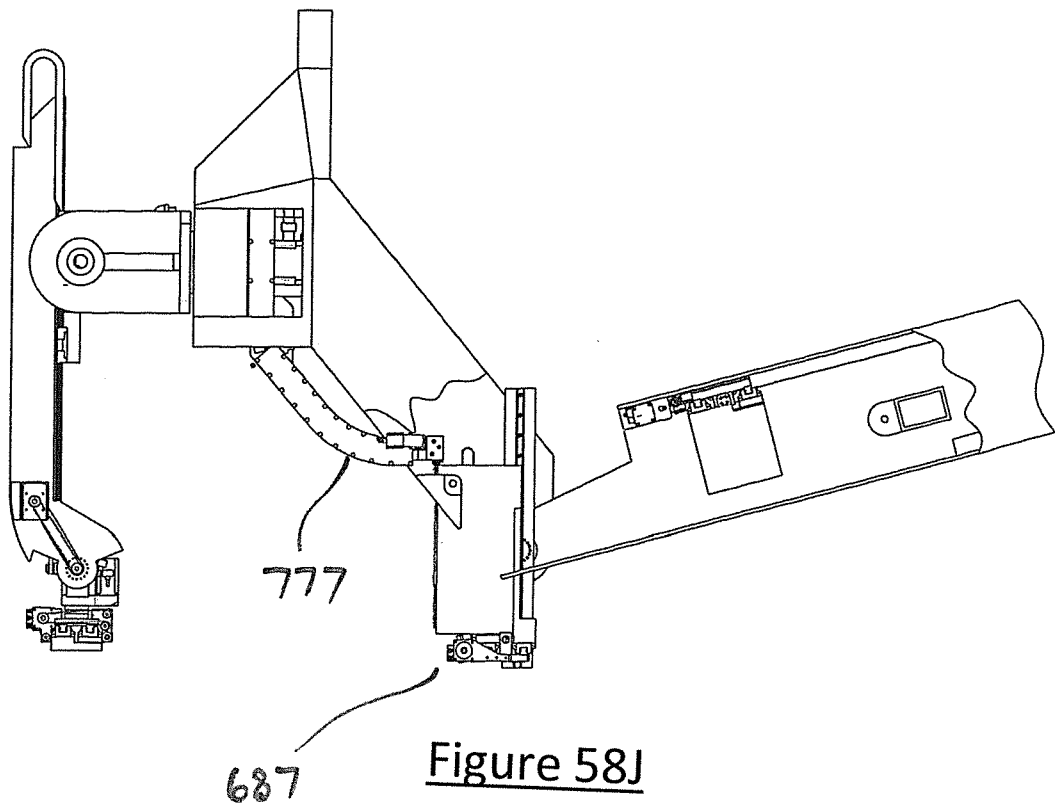
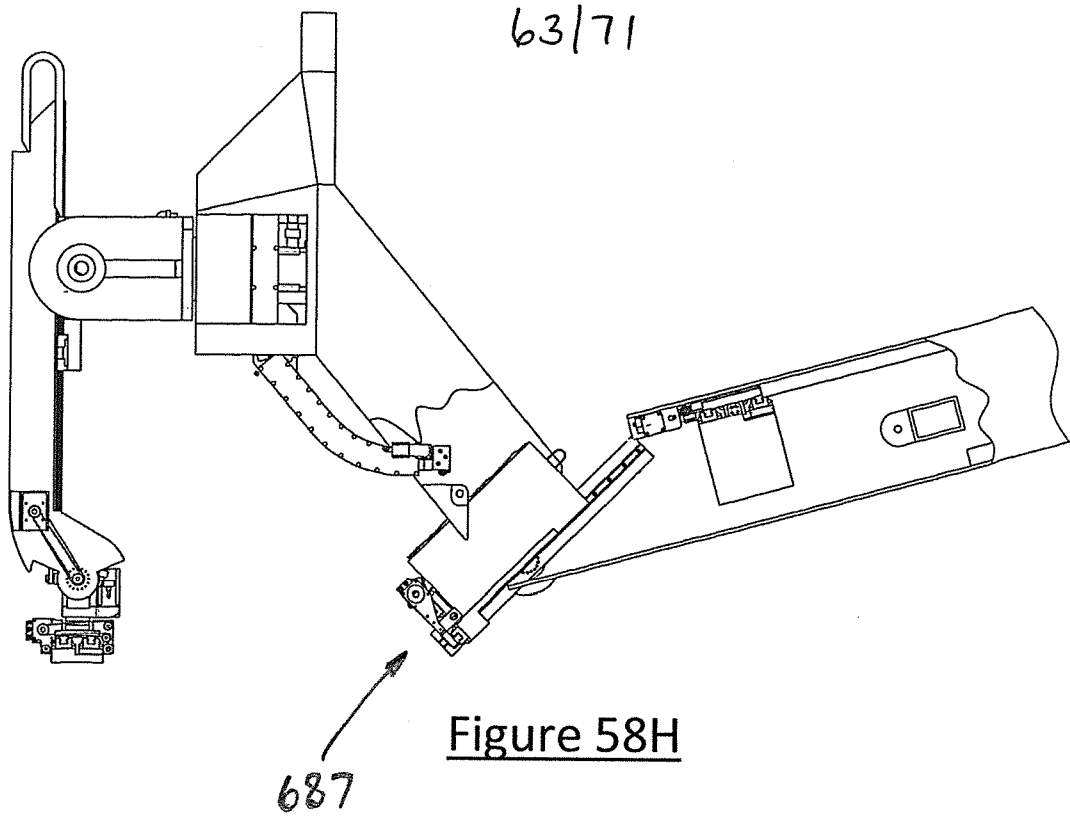


Figure 58G



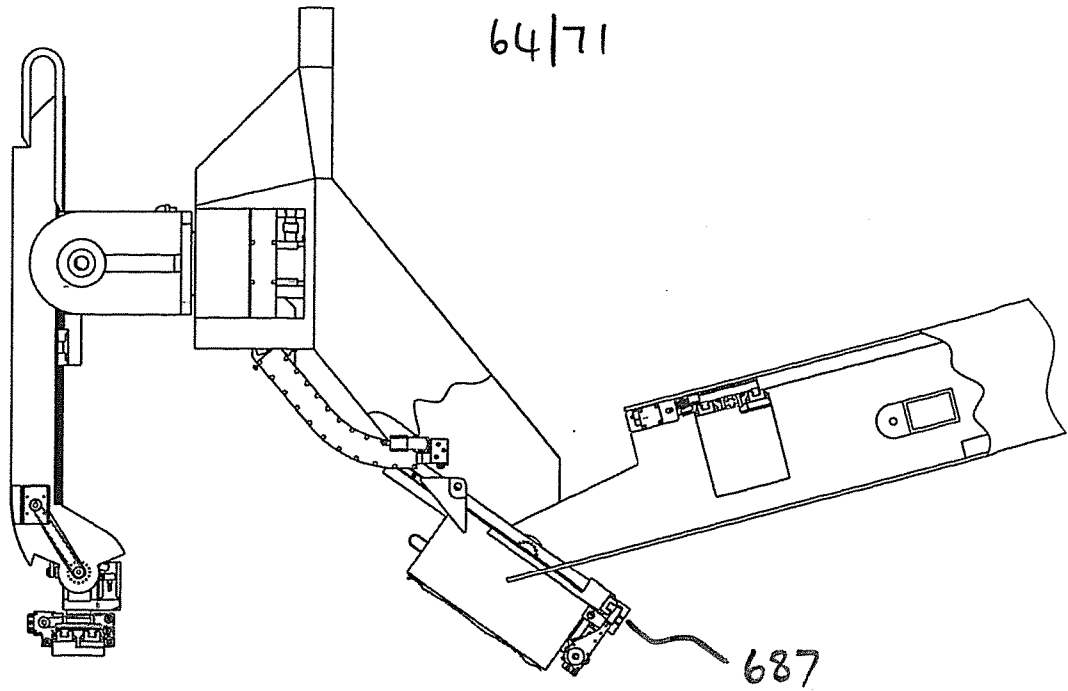


Figure 58K

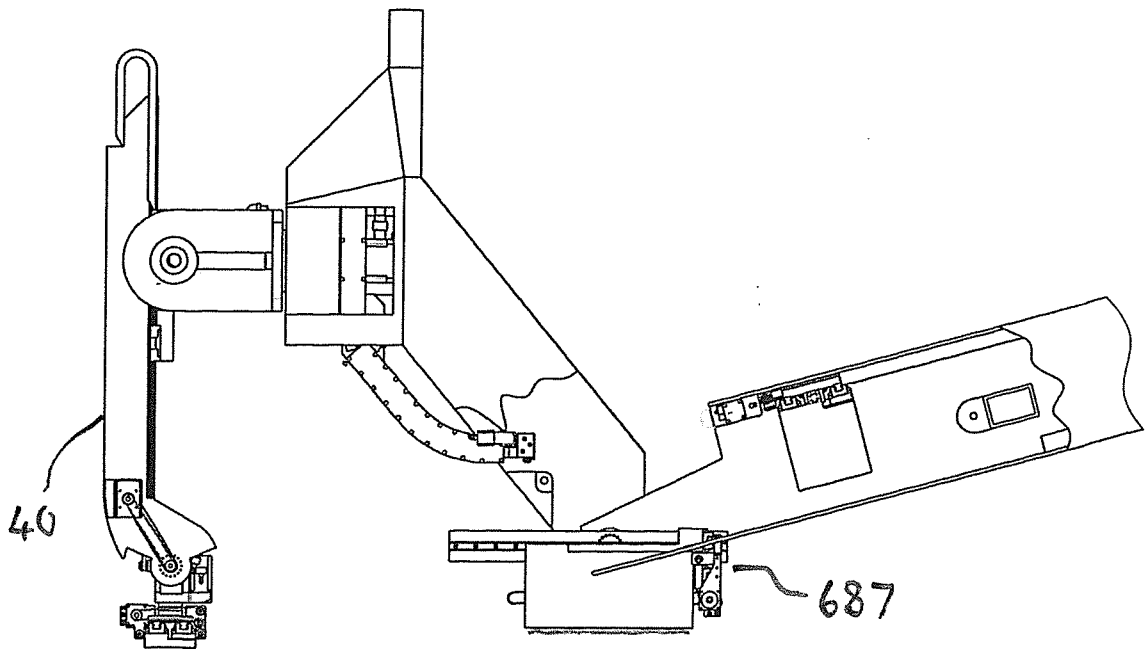
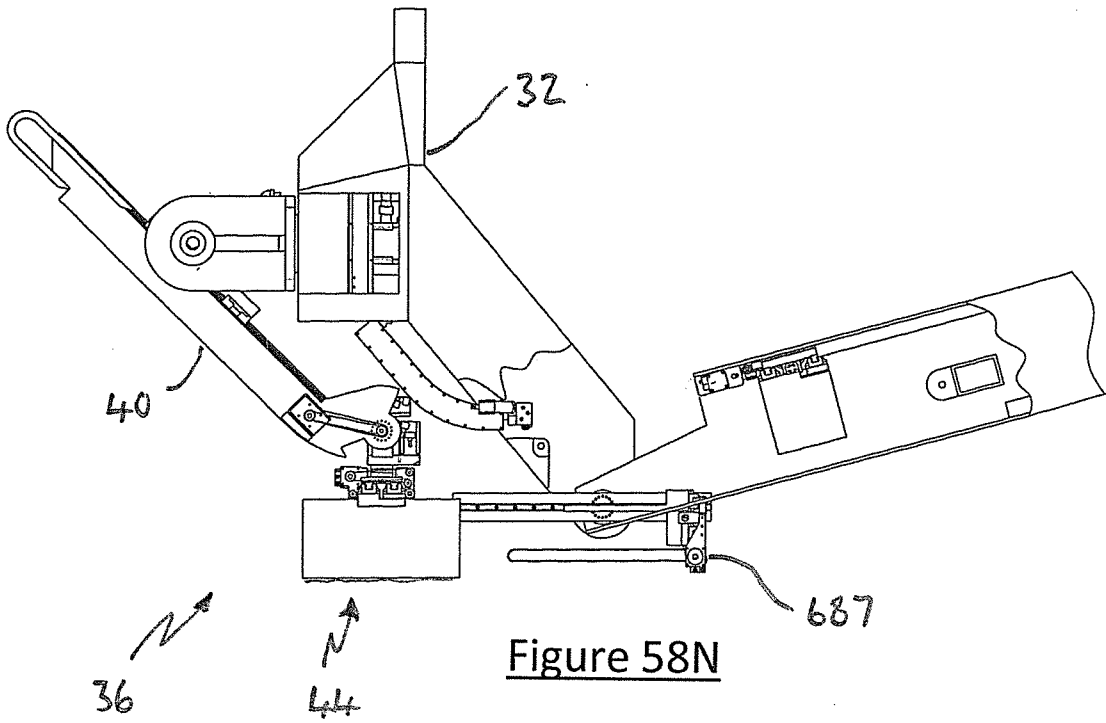
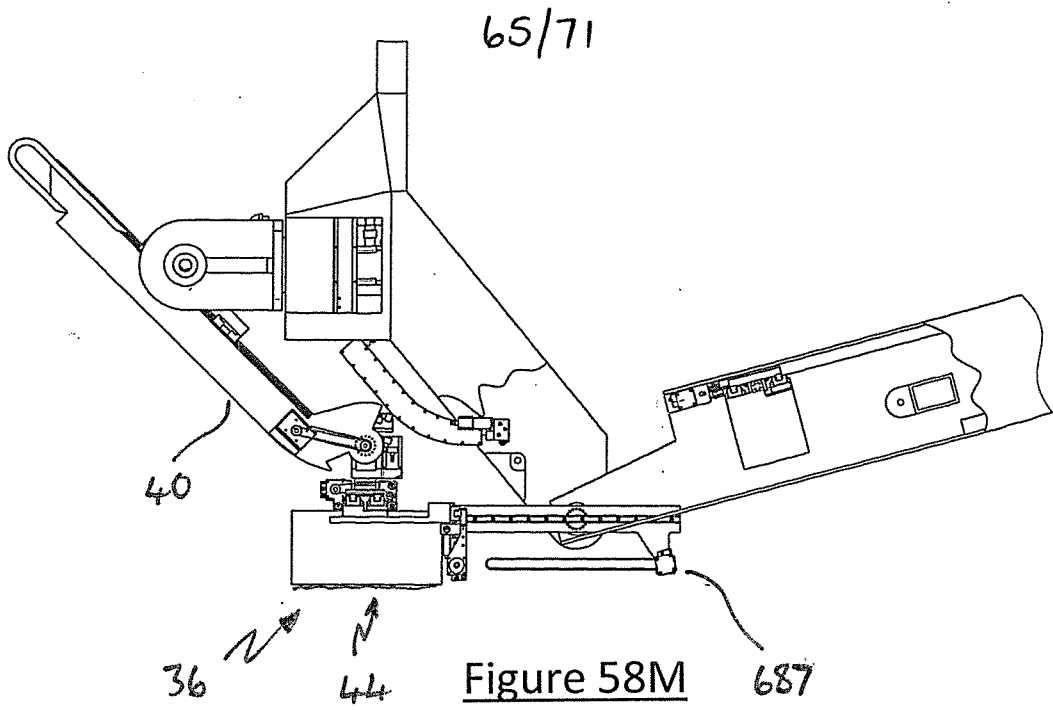


Figure 58L



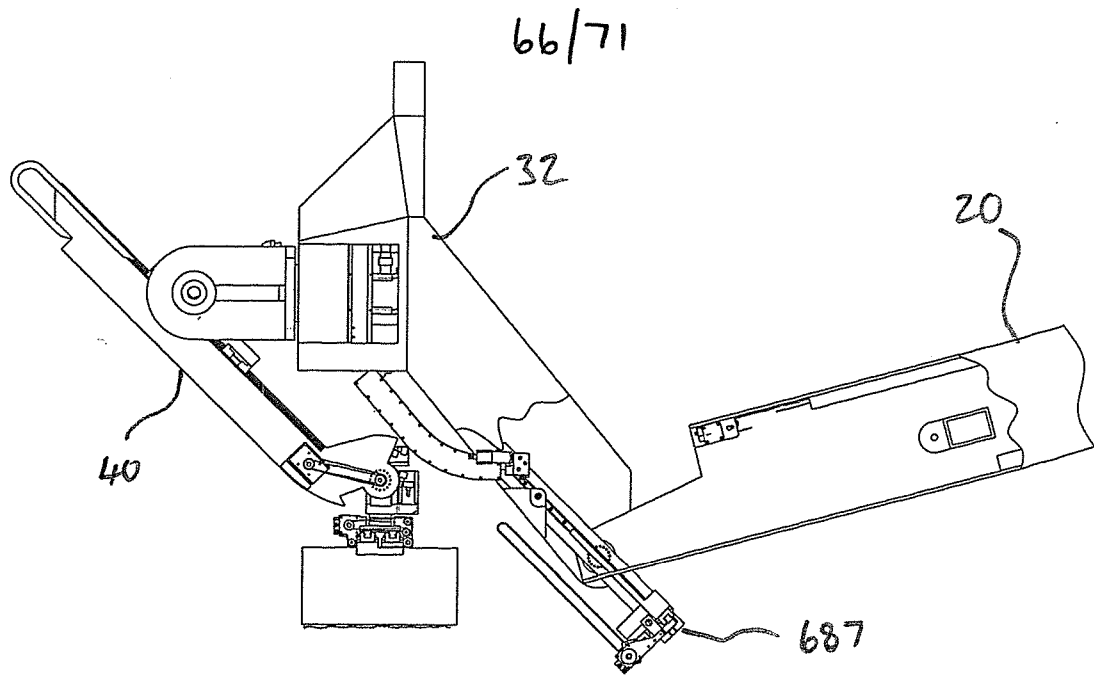


Figure 58P

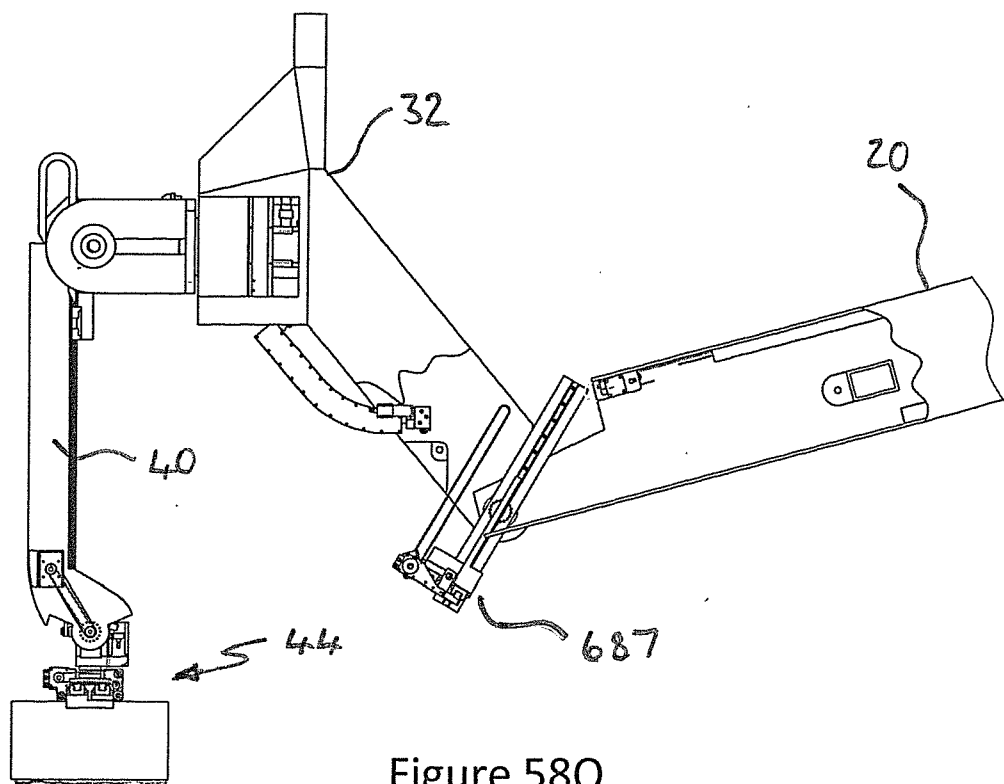


Figure 58Q

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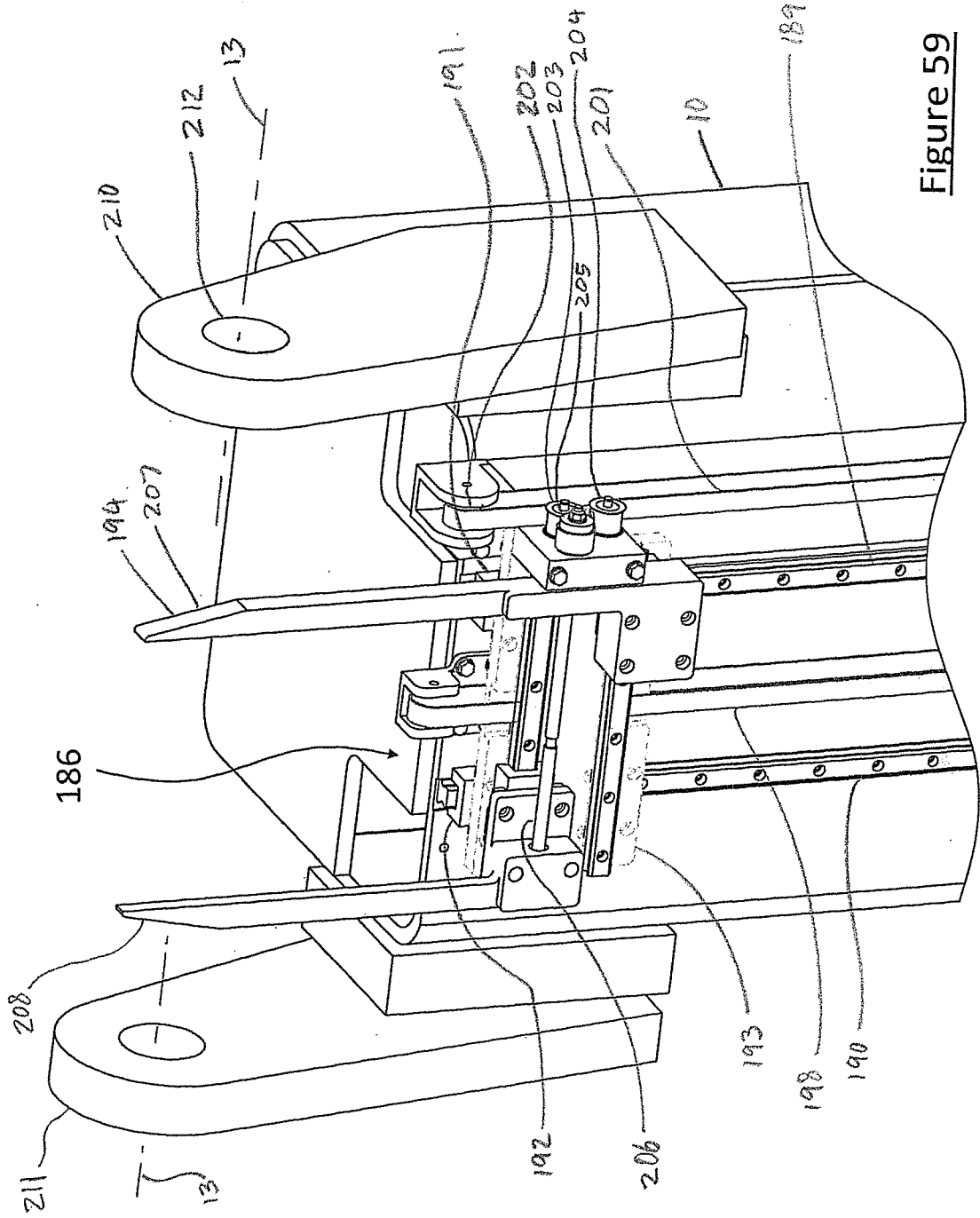


Figure 59

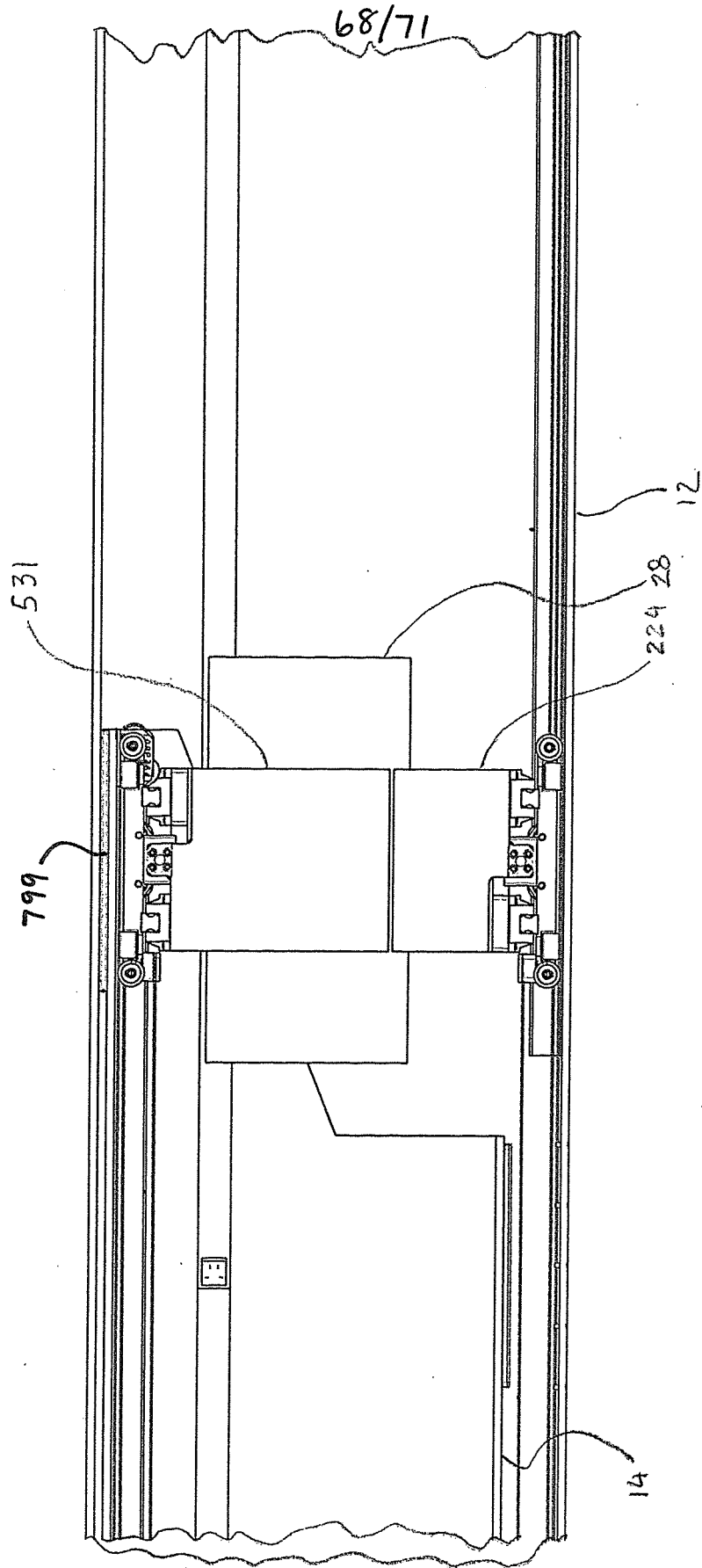


Figure 60

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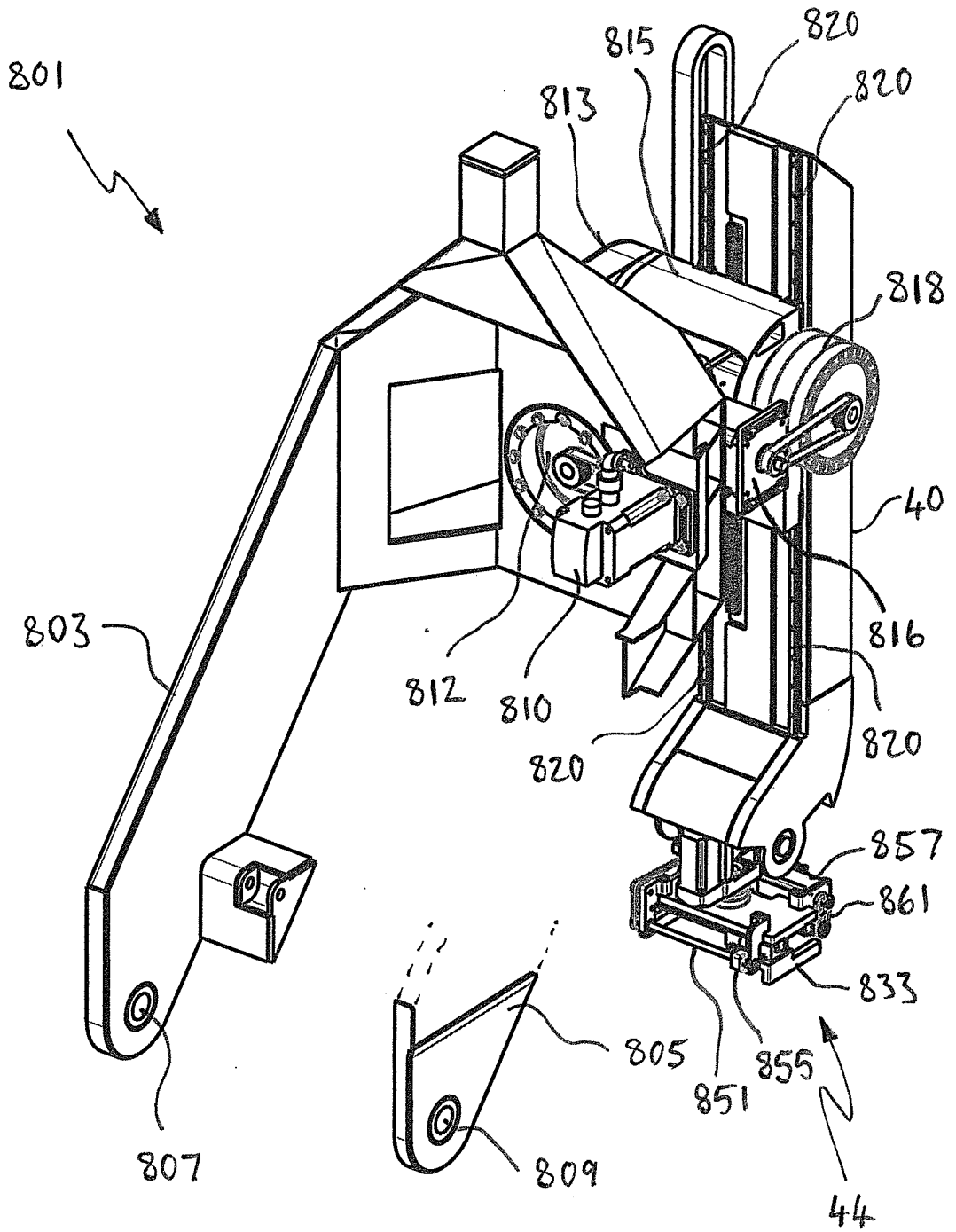


Figure 61

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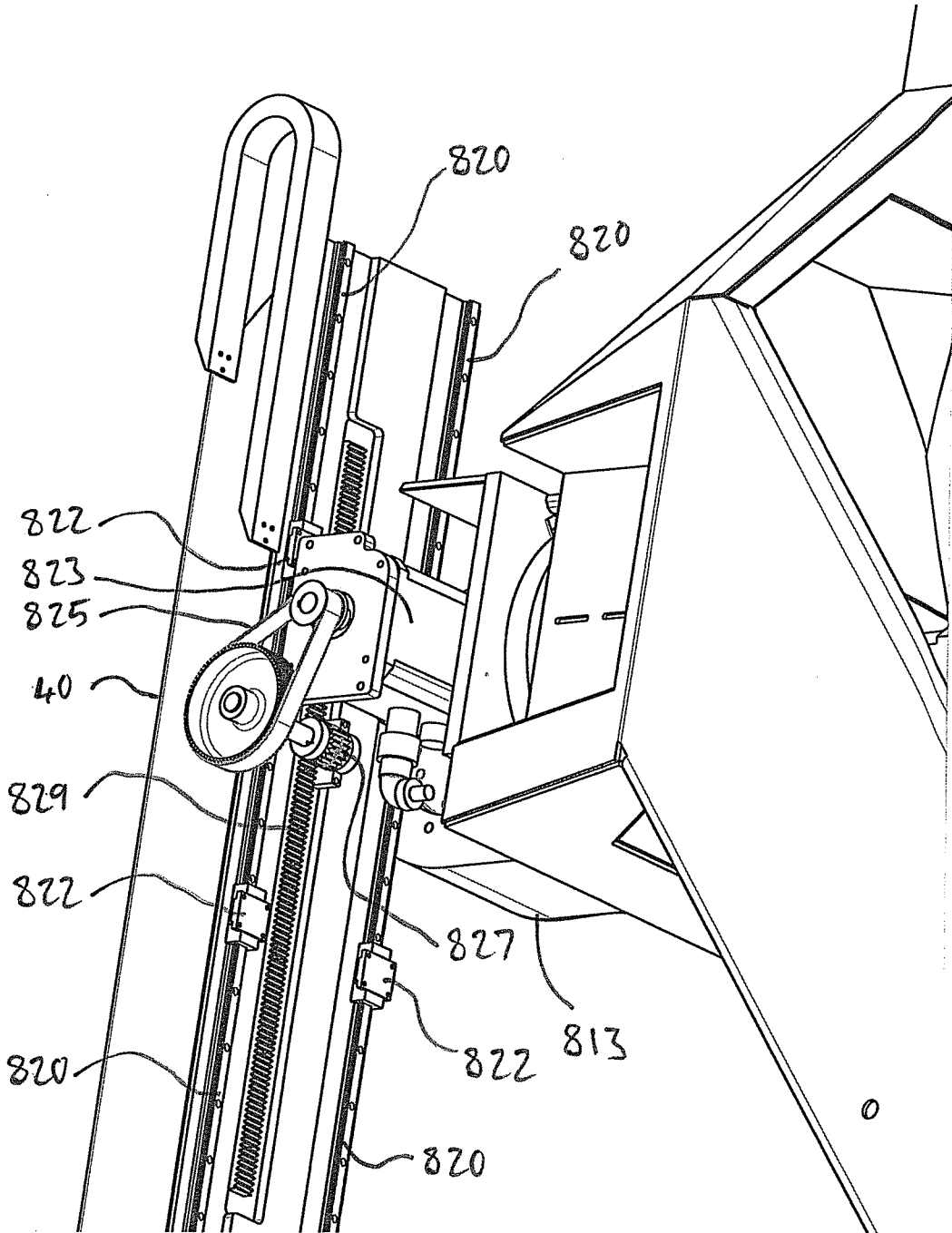


Figure 62

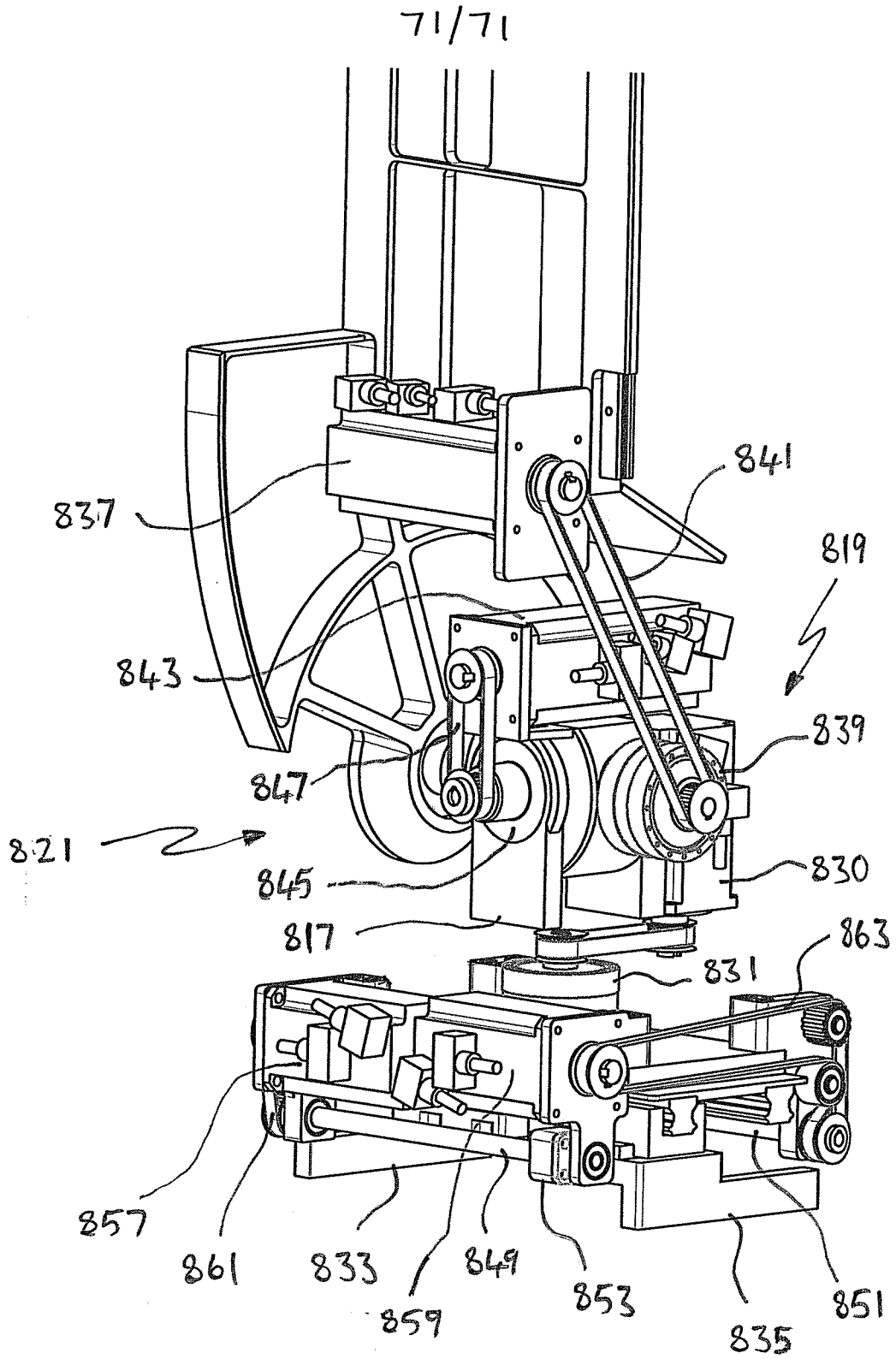


Figure 63

INTERNATIONAL SEARCH REPORT

International application No.

PCT/AU2017/050728

A. CLASSIFICATION OF SUBJECT MATTER

E04G 21/22 (2006.01) E04G 21/20 (2006.01) E04G 21/04 (2006.01) E04G 21/14 (2006.01) B25J 18/02 (2006.01)
B25J 18/06 (2006.01) B05B 13/04 (2006.01)

According to International Patent Classification (IPC) or to both national classification and IPC

B. FIELDS SEARCHED

Minimum documentation searched (classification system followed by classification symbols)

Documentation searched other than minimum documentation to the extent that such documents are included in the fields searched

Electronic data base consulted during the international search (name of data base and, where practicable, search terms used)

Database: **PATENW (EPOQUE INTERNAL)**; IPC/CPC/low: E04G21/[04, 0445, 14, 20, 22], G05B2219/45086, Y10S901/43, B25J11/0075, B25J18/[02,06], B05B15/[08, 10], B05B3/18, B05B13/04, B282B1/001, B33Y, B05B, B05B3, B05B13, B25J, E04; KW: articulate, pivot, turn, rotate, revolve, swivel, grip, clamp, vice, manipulate, grasp, handling, block, slab, element, panel, brick, spray, apply, dispense, nozzle, concrete, cement, mortar, grout, aggregate, adhesive, glue, gluing, bonding, weld, extend, retract, telescope, withdraw, arm, boom, tongue, head, sheath, sleeve, chain, actuator and similar terms; Databases: **Espacenet (Worldwide)/AusPat/Internal databases provided by IP Australia**; Applicant/Inventor name searched; Database: **Espacenet (Worldwide)**; E04G21/22 with KWs: concrete, cement, mortar, adhesive, spray, apply, dispense, nozzle, clamp, grip, vice, grasp, claw, block, brick, slab, element and similar terms; Database: **Google Patents**; KWs: adhesive, mortar, nozzle, apply, brick-laying, block, robot, machine, manipulate, clamp, vice, grip and similar terms; Google internet search, Query: Fastbrick. Cited and citing done on most relevant art.

C. DOCUMENTS CONSIDERED TO BE RELEVANT

Category*	Citation of document, with indication, where appropriate, of the relevant passages	Relevant to claim No.
	Documents are listed in the continuation of Box C	

 Further documents are listed in the continuation of Box C See patent family annex

* Special categories of cited documents:		
"A" document defining the general state of the art which is not considered to be of particular relevance	"T"	later document published after the international filing date or priority date and not in conflict with the application but cited to understand the principle or theory underlying the invention
"E" earlier application or patent but published on or after the international filing date	"X"	document of particular relevance; the claimed invention cannot be considered novel or cannot be considered to involve an inventive step when the document is taken alone
"L" document which may throw doubts on priority claim(s) or which is cited to establish the publication date of another citation or other special reason (as specified)	"Y"	document of particular relevance; the claimed invention cannot be considered to involve an inventive step when the document is combined with one or more other such documents, such combination being obvious to a person skilled in the art
"O" document referring to an oral disclosure, use, exhibition or other means	"&"	document member of the same patent family
"P" document published prior to the international filing date but later than the priority date claimed		

Date of the actual completion of the international search
28 September 2017

Date of mailing of the international search report
28 September 2017

Name and mailing address of the ISA/AU

AUSTRALIAN PATENT OFFICE
PO BOX 200, WODEN ACT 2606, AUSTRALIA
Email address: pct@ipaustralia.gov.au

Authorised officer

Matthew McTiernan
AUSTRALIAN PATENT OFFICE
(ISO 9001 Quality Certified Service)
Telephone No. +61262256103

INTERNATIONAL SEARCH REPORT		International application No. PCT/AU2017/050728
C (Continuation). DOCUMENTS CONSIDERED TO BE RELEVANT		
Category*	Citation of document, with indication, where appropriate, of the relevant passages	Relevant to claim No.
X	Fastbrick Robotics: Hadrian 105 Time Lapse [Viewed on internet on 20 August 2017] Viewed on internet < URL: https://www.youtube.com/watch?v=4YcrO8ONcfY >, Published on 22 May 2016 video at time 0:15-0:51	11-17
A	US 2010/0025349 A1 (KHOSHNEVIS) 04 February 2010 figs. 5A & 12 and paragraphs [0056], [0064]	1-10
A	US 2013/0068061 A1 (YOON) 21 March 2013 fig. 1	1-10
A	US 3950914 A (LOWEN) 20 April 1976 abstract, description: col. 2, lines 31-39; col. 5, lines 3-66 & figs. 1-3 & 6-11	1-18
A	Fastbrick Robotics: Hadrian 105 First Look Revealed [Viewed on internet on 20 August 2017] Viewed on internet. < URL: https://www.youtube.com/watch?v=7Zw7qHxMtrY >, Published on 16 November 2015 see video at time: 3:25-3:40	1-18
A	US 2009/0038258 A1 (PIVAC et al.) 12 February 2009 abstract and figs. 1-6	1-18
A	US 8825208 B1 (BENSON) 02 September 2014 abstract and figs. 1-5, 8 & 9	1-18
A	CH 673498 A5 (THOMAS ALBERT PFISTER) 15 March 1990, English translation retrieved from Espacenet abstract and fig. 1	1-18
A	US 2012/0038074 A1 (KHOSHNEVIS) 16 February 2012 abstract and figs. 1-9	1-18
A	US 5284000 A (MILNE et al.) 08 February 1994 abstract and figs. 9-13	1-18

Box No. II Observations where certain claims were found unsearchable (Continuation of item 2 of first sheet)

This international search report has not been established in respect of certain claims under Article 17(2)(a) for the following reasons:

1. Claims Nos.:
because they relate to subject matter not required to be searched by this Authority, namely:
the subject matter listed in Rule 39 on which, under Article 17(2)(a)(i), an international search is not required to be carried out, including
2. Claims Nos.:
because they relate to parts of the international application that do not comply with the prescribed requirements to such an extent that no meaningful international search can be carried out, specifically:
3. Claims Nos.:
because they are dependent claims and are not drafted in accordance with the second and third sentences of Rule 6.4(a)

Box No. III Observations where unity of invention is lacking (Continuation of item 3 of first sheet)

This International Searching Authority found multiple inventions in this international application, as follows:

See Supplemental Box for Details

1. As all required additional search fees were timely paid by the applicant, this international search report covers all searchable claims.
2. As all searchable claims could be searched without effort justifying additional fees, this Authority did not invite payment of additional fees.
3. As only some of the required additional search fees were timely paid by the applicant, this international search report covers only those claims for which fees were paid, specifically claims Nos.:
4. No required additional search fees were timely paid by the applicant. Consequently, this international search report is restricted to the invention first mentioned in the claims; it is covered by claims Nos.:

Remark on Protest

- The additional search fees were accompanied by the applicant's protest and, where applicable, the payment of a protest fee.
- The additional search fees were accompanied by the applicant's protest but the applicable protest fee was not paid within the time limit specified in the invitation.
- No protest accompanied the payment of additional search fees.

Supplemental Box**Continuation of: Box III**

This International Application does not comply with the requirements of unity of invention because it does not relate to one invention or to a group of inventions so linked as to form a single general inventive concept.

This Authority has found that there are different inventions based on the following features that separate the claims into distinct groups:

•Claims 1-10 (and claim 18 in part) are directed to an adhesive applicator tool for machine application of adhesive. The feature of the adhesive applicator head having at least one nozzle fed with adhesive under pressure for selective application to a surface, said adhesive applicator head being supported on a distal end of a tongue member, said tongue member being housed in a sheath for linear movement to extend said adhesive applicator head across said surface for application of adhesive, and retract said tongue within said sheath to withdraw said adhesive applicator head away from said surface, said tongue being rigid when extended obliquely or horizontally and freely deflectable in only one dimension upwardly, about horizontal axes is specific to this group of claims.

•Claims 11-17 (and claim 18 in part) are directed to a brick laying and adhesive applying head for a bricklaying machine. The feature of the adhesive applying head having a clevis with a horizontal axis for pivot mounting for controlled rotation to the remote end of a boom, said brick laying and adhesive applying head including a pivotable clamp to receive and clamp a brick presented at the remote end of said boom, said pivotable clamp being pivotally mounted about said horizontal axis; said brick laying and adhesive applying head supporting an adhesive applicator tool aligned to extend said adhesive applicator across a brick presented by said pivotable clamp; said brick laying and adhesive applying head having a brick laying head mounted thereto by a mount located in a position away from said clevis, said brick laying head having a brick laying clamp moveable between a position to receive and clamp a brick held by said pivotable clamp, to a position in which said brick is released and laid is specific to this group of claims.

PCT Rule 13.2, first sentence, states that unity of invention is only fulfilled when there is a technical relationship among the claimed inventions involving one or more of the same or corresponding special technical features. PCT Rule 13.2, second sentence, defines a special technical feature as a feature which makes a contribution over the prior art.

When there is no special technical feature common to all the claimed inventions there is no unity of invention.

In the above groups of claims, the identified features may have the potential to make a contribution over the prior art but are not common to all the claimed inventions and therefore cannot provide the required technical relationship. The only feature common to all of the claimed inventions and which provides a technical relationship among them is an adhesive applying head. However this feature does not make a contribution over the prior art because it is considered generic in the art, for example see: D1 – in video at 0:33-0:40 and D2 – figs. 5A & 12 and paragraphs [0056], [0064].

Therefore in the light of these documents this common feature cannot be a special technical feature. Therefore there is no special technical feature common to all the claimed inventions and the requirements for unity of invention are consequently not satisfied *a posteriori*.

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		GB 1465068 A	23 Feb 1977
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