

Accerion

The fast-growing mobile robotics industry requires solutions to be increasingly mobile and autonomous

This has started a trend towards infrastructure free navigation

Current systems require recognizable landmarks in the environment

We want to go one step further

Accerion's technology uses advanced optical technology to scan the floor surface

This determines movement, position and orientation of the robot or vehicle, which is communicated to the navigation system

Accerion enables new modes of navigation, including:

- Indoor and outdoor navigation with a single system
- Large spaces (e.g., warehouses, shipyards)
- Dynamic environments (e.g., moving people, equipment, material)

"A sensor module that can easily be integrated in existing mobile robots and AGVs"



Technology

Measurement principle

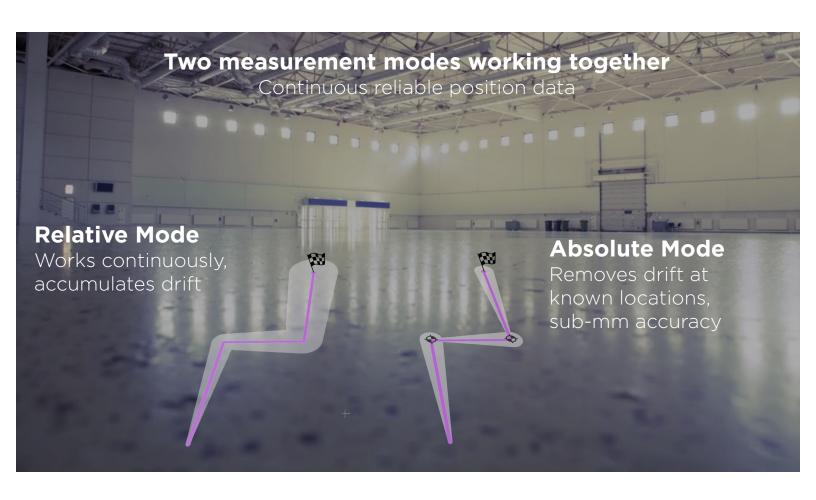
- · Advanced optical system, using floor surface as reference
- · Determines location, orientation and movement

Reaching Absolute position

- Relative measurement with continuous drift correction
- Recognises known areas of the floor surface, without markers

Operation

- Infrastructure free, position immediately found after power-up
- Robust in coping with gradual floor changes (dirt, wear)
- Immediate deployment of additional robots in the same operation



Specifications

Jupiter

Accuracy

Relative Absolute >99.8%

10mm continuous sub-mm at area of interest

W.

Power consumption

<30W (9-32V_{DC})

Communication Protocol

Ethernet, ROS (on request: EtherCat, CAN, RS-232, custom)

Geometry

Components

Weight 2

Volume (HxWxD)
Clearance to ground

1 single sensor module

2.4 kg

90x120x300 mm

75 mm (custom on request)

40.000m² (higher on request)

Environments

Floor surface

Air quality Temperature

IP rating

Light

Industrial surfaces (indoor &

outdoor)

Industrial environments

-10°C - 50°C

IP65 (IP67 on request) No impact from external light

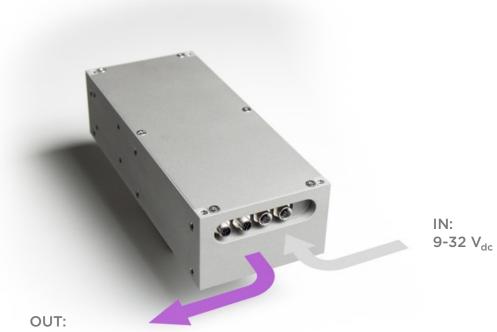
Vehicle speed

2m/s

Delivery time

small quantity on stock, avg. 4

weeks from order



position: x, y, θ velocity: v_x, v_y, v_θ