

(12) 按照专利合作条约所公布的国际申请

(19) 世界知识产权组织
国际局



(10) 国际公布号
WO 2025/107515 A1

(43) 国际公布日
2025 年 5 月 30 日 (30.05.2025)

- (51) 国际专利分类号:
B65G 1/04 (2006.01) **B65G 1/137** (2006.01)
- (21) 国际申请号: PCT/CN2024/090386
- (22) 国际申请日: 2024 年 4 月 28 日 (28.04.2024)
- (25) 申请语言: 中文
- (26) 公布语言: 中文
- (30) 优先权:
202311575043.8 2023 年 11 月 23 日 (23.11.2023) CN
- (71) 申请人: 浙江立镖机器人有限公司 (ZHEJIANG LIBIAO ROBOTICS CO., LTD.) [CN/CN]; 中国浙江省杭州市临平区临平街道昌达路 96 号 311199 (CN)。
- (72) 发明人: 朱建强 (ZHU, Jianqiang); 中国浙江省杭州市临平区临平街道昌达路 96 号 311199 (CN)。

- (74) 代理人: 北京超凡宏宇知识产权代理有限公司 (CHOFN INTELLECTUAL PROPERTY); 中国北京市海淀区北四环西路 68 号左岸工社 1215-1218 室 100080 (CN)。
- (81) 指定国(除另有指明, 要求每一种可提供的国家保护): AE, AG, AL, AM, AO, AT, AU, AZ, BA, BB, BG, BH, BN, BR, BW, BY, BZ, CA, CH, CL, CN, CO, CR, CU, CV, CZ, DE, DJ, DK, DM, DO, DZ, EC, EE, EG, ES, FI, GB, GD, GE, GH, GM, GT, HN, HR, HU, ID, IL, IN, IQ, IR, IS, IT, JM, JO, JP, KE, KG, KH, KN, KP, KR, KW, KZ, LA, LC, LK, LR, LS, LU, LY, MA, MD, MG, MK, MN, MU, MW, MX, MY, MZ, NA, NG, NI, NO, NZ, OM, PA, PE, PG, PH, PL, PT, QA, RO, RS, RU, RW, SA, SC, SD, SE, SG, SK, SL, ST, SV, SY, TH, TJ, TM, TN, TR, TT, TZ, UA, UG, US, UZ, VC, VN, WS, ZA, ZM, ZW。
- (84) 指定国(除另有指明, 要求每一种可提供的地区保护): ARIPO (BW, CV, GH, GM, KE, LR, LS, MW, MZ,

(54) Title: IN-WAREHOUSE PICKING CONTROL METHOD AND SYSTEM

(54) 发明名称: 在库拣选控制方法和系统

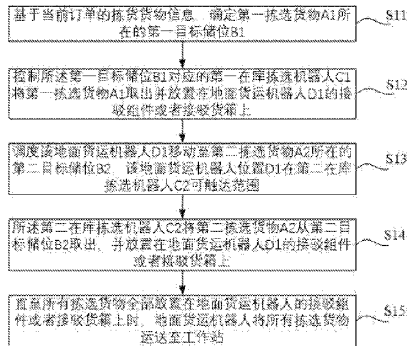


图 3

- S11 On the basis of picked-goods information of the current order, determine a first target storage location B1 where first picked goods A1 are located
- S12 Control a first in-warehouse picking robot C1 corresponding to the first target storage location B1 to pick up the first picked goods A1 and place same onto a transferring assembly or transferring goods box of a ground freight robot D1
- S13 Dispatch the ground freight robot D1 to move to a second target storage location B2 where second picked goods A2 are located, wherein the ground freight robot D1 is located within a reachable range of a second in-warehouse picking robot C2
- S14 The second in-warehouse picking robot C2 picks up the second picked goods A2 from the second target storage location B2 and places the second picked goods onto the transferring assembly or transferring goods box of the ground freight robot D1
- S15 It is only after all picked goods are placed on the transferring assembly or transferring goods box of the ground freight robot that the ground freight robot transports all the picked goods to a workstation

(57) Abstract: An in-warehouse picking control method and system. The method is applied to a stereoscopic warehouse, which comprises a plurality of racks (10), wherein each rack (10) is provided with a plurality of layers of storage spaces (101), and goods boxes (104) are placed at storage locations in the storage spaces (101). According to the current order, a control server is configured to: on the basis of picked-goods information of the current order, determine a first target storage location (B1) where first picked goods (A1) are located; control a first in-warehouse picking robot (C1) corresponding to the first target storage location (B1) to pick up the first picked goods (A1) and place same onto a transferring assembly or transferring goods box of a ground freight robot (D1); dispatch the ground freight robot (D1) to move to a second target storage location (B2) where second picked goods (A2) are located, wherein the ground freight robot (D1) is located within a reachable range of a second in-warehouse picking robot (C2); control the second in-warehouse picking robot (C2) to pick up the second picked goods (A2) from the second target storage location (B2) and place the second picked goods onto the transferring assembly or transferring goods box of the ground freight robot (D1); and repeat the above steps to complete a rapid order fulfillment and outbound process.

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NA, RW, SC, SD, SL, ST, SZ, TZ, UG, ZM, ZW), 欧亚
(AM, AZ, BY, KG, KZ, RU, TJ, TM), 欧洲 (AL, AT, BE,
BG, CH, CY, CZ, DE, DK, EE, ES, FI, FR, GB, GR, HR,
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TD, TG)。

本国际公布:
— 包括国际检索报告(条约第21条(3))。

(57) 摘要: 一种在库拣选控制方法及系统, 该方法用于立体仓库, 该立体仓库包括多个货架(10), 该货架(10)设置有多层存储空间(101), 并在存储空间(101)的储位放置货箱(104), 根据当前订单: 该控制服务器配置为, 基于当前订单的拣货货物信息, 确定第一拣选货物(A1)所在的第一目标储位(B1); 控制该第一目标储位(B1)对应的第一在库拣选机器人(C1)将第一拣选货物(A1)取出并放置在地面货运机器人(D1)的接驳组件或者接驳货箱上; 调度该地面货运机器人(D1)移动至第二拣选货物(A2)所在的第二目标储位(B2), 该地面货运机器人(D1)位置在第二在库拣选机器人(C2)可触达范围; 该第二在库拣选机器人(C2)将第二拣选货物(A2)从第二目标储位(B2)取出, 并放置在地面货运机器人(D1)的接驳组件或者接驳货箱上; 循环上述步骤以完成快速履约出库。