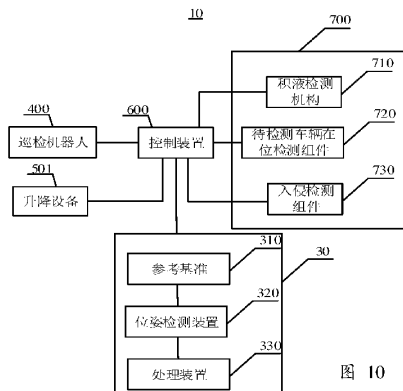


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(81) 指定国(除另有指明, 要求每一种可提供的国家保护): AE, AG, AL, AM, AO, AT, AU, AZ, BA, BB, BG, BH, BN, BR, BW, BY, BZ, CA, CH, CL, CN, CO, CR, CU,

(54) 发明名称: 轨道交通机车车辆巡检位姿检测系统及其方法



310	Reference datum
320	Pose inspection device
330	Processing device
400	Inspection robot
501	Lifting device
600	Control device
710	Effusion detection mechanism
720	Inspected vehicle presence detection component
730	Intrusion detection component

(57) Abstract: Provided is a rail transit locomotive vehicle inspection pose detection system. Comprising: a reference datum (310), a pose detection device (320) and a processing device (330). The reference datum (310) is arranged on one side of the rail along the extending direction of the rail where a vehicle to be detected is parked. The pose detection device (320) is arranged on a rail transit locomotive vehicle inspection robot (400), and is used to detect distance information of the rail transit locomotive vehicle inspection robot (400) relative to the reference datum (310). The processing device (330) is in communication connection with the pose detection

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- (84) 指定国(除另有指明, 要求每一种可提供的地区保护): ARIPO (BW, GH, GM, KE, LR, LS, MW, MZ, NA, RW, 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, HU, IE, IS, IT, LT, LU, LV, MC, MK, MT, NL, NO, PL, PT, RO, RS, SE, SI, SK, SM, TR), OAPI (BF, BJ, CF, CG, CI, CM, GA, GN, GQ, GW, KM, ML, MR, NE, SN, TD, TG)。

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device (320), and is used to calculate the pose offset of the rail transit locomotive vehicle inspection robot (400) relative to a reference coordinate according to the distance information of the rail transit locomotive vehicle inspection robot (400) relative to the reference datum (310). The rail transit locomotive vehicle inspection pose detection system can implement pose offset detection and provide high accuracy. Further provided is a rail transit locomotive vehicle inspection pose detection method.

(57) 摘要: 一种轨道交通机车车辆巡检位姿检测系统。包括: 参考基准(310)、位姿检测装置(320)和处理装置(330)。参考基准(310)沿待检测车辆停放的轨道延伸方向设置于所述轨道一侧。位姿检测装置(320)设置于轨道交通机车车辆巡检机器人(400), 用于检测轨道交通机车车辆巡检机器人(400)相对于参考基准(310)的距离信息。处理装置(330)与位姿检测装置(320)通信连接, 用于根据轨道交通机车车辆巡检机器人(400)相对于参考基准(310)的距离信息计算轨道交通机车车辆巡检机器人(400)相对于基准坐标的位姿偏移量。该轨道交通机车车辆巡检位姿检测系统能够实现位姿偏移量检测, 且精确度高。还提供一种轨道交通机车车辆巡检位姿检测方法。