

ABSTRACT

The present application provides a polishing robot, and relates to the technical field of architectural robots. The polishing robot includes a chassis and two spindles. A top end of each spindle of the two spindles is provided with a universal connector connected to the chassis, the
5 universal connector is rotatably connected to the chassis along the axis direction, a bottom end of the each spindle of the two spindles is used for connecting a leaf-blade component, each spindle of the two spindles is respectively provided with a first reversing mechanism, and at least one of the two spindles is provided with a second reversing mechanism. The first reversing mechanism is connected to the chassis and is configured to drive each spindle to swing around a
10 Y-axis direction, the second reversing mechanism is connected to the first reversing mechanism and is configured to drive a corresponding spindle to swing around an X-axis direction, and axes of the two spindles are arranged in the X-axis direction. The above arrangement can drive the polishing robot to translate, turn and rotate in situ, so that the operation flexibility is high, and the polishing robot can achieve the omnidirectional movement in the polishing process, and
15 the processing capability at the corn of the work surface is effectively improved.

Fig. 1