

(12) INTERNATIONAL APPLICATION PUBLISHED UNDER THE PATENT COOPERATION TREATY (PCT)

(19) World Intellectual Property
Organization
International Bureau

(43) International Publication Date
27 March 2025 (27.03.2025)



(10) International Publication Number
WO 2025/064800 A1

(51) International Patent Classification:
B25J 9/16 (2006.01) *B25J 9/00* (2006.01)
B25J 11/00 (2006.01)

(21) International Application Number:
PCT/US2024/047669

(22) International Filing Date:
20 September 2024 (20.09.2024)

(25) Filing Language: English

(26) Publication Language: English

(30) Priority Data:
63/539,883 22 September 2023 (22.09.2023) US
63/619,169 09 January 2024 (09.01.2024) US
18/890,367 19 September 2024 (19.09.2024) US

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(81) Designated States (*unless otherwise indicated, for every kind of national protection available*): 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,

(54) Title: SYSTEMS AND METHODS FOR CONTROLLING A ROBOT

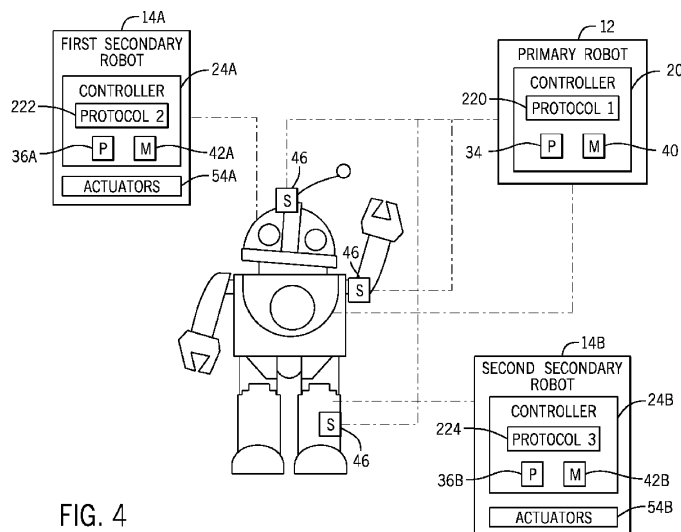


FIG. 4

(57) Abstract: A multi-sectional robot 16 includes a first robot 12 configured to communicate via a first protocol 220 and a second robot 14 coupled to the first robot 12 and configured to communicate via a second protocol 222. Further, the multi-sectional robot 16 includes a controller 20 that operates based on a third protocol, receives movement commands to move the multi-sectional robot 16, determines a status of the multi-sectional robot 16, determines an operational profile for the first robot 12 and the second robot 14 based on the movement commands and the status, translates at least a first portion of the operational profile from the third protocol to a first translation in the first protocol 220, translates at least a second portion of the operational profile from the third protocol to a second translation in the second protocol 222, outputs the first translation to the first robot 12 as first operational instructions, and outputs the second translation to the second robot 14 as second operational instructions.

[Continued on next page]

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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) Designated States (*unless otherwise indicated, for every kind of regional protection available*): ARIPO (BW, CV, GH, GM, KE, LR, LS, MW, MZ, NA, RW, SC, SD, SL, ST, SZ, TZ, UG, ZM, ZW), Eurasian (AM, AZ, BY, KG, KZ, RU, TJ, TM), European (AL, AT, BE, BG, CH, CY, CZ, DE, DK, EE, ES, FI, FR, GB, GR, HR, HU, IE, IS, IT, LT, LU, LV, MC, ME, 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).

Published:

- with international search report (Art. 21(3))
 - before the expiration of the time limit for amending the claims and to be republished in the event of receipt of amendments (Rule 48.2(h))
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