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<p>(51) International classification :B62B0005000000, H04N0007180000, G05D0001020000, A23N0005030000, B25J0013080000</p> <p>(86) International Application No :NA Filing Date :NA</p> <p>(87) International Publication No : NA</p> <p>(61) Patent of Addition to Application Number :NA Filing Date :NA</p> <p>(62) Divisional to Application Number :NA Filing Date :NA</p>	<p>(71)Name of Applicant : 1)Jaipur National University Address of Applicant :Jaipur-Agra Bypass, Near New RTO office, Jagatpura, Jaipur-302017, Rajasthan, India. Jaipur ----- -----</p> <p>Name of Applicant : NA Address of Applicant : NA</p> <p>(72)Name of Inventor : 1)Prof. Divya Shrivastava Address of Applicant :School of Life & Basic Sciences, Jaipur National University, Jaipur-Agra Bypass, Near New RTO office, Jagatpura, Jaipur-302017, Rajasthan, India. Jaipur ----- -----</p> <p>2)Prof. Indrani Jadhav Address of Applicant :School of Life & Basic Sciences, Jaipur National University, Jaipur-Agra Bypass, Near New RTO office, Jagatpura, Jaipur-302017, Rajasthan, India. Jaipur ----- -----</p> <p>3)Dr. Meenal Rehman Address of Applicant :School of Life & Basic Sciences, Jaipur National University, Jaipur-Agra Bypass, Near New RTO office, Jagatpura, Jaipur-302017, Rajasthan, India. Jaipur ----- -----</p> <p>4)Suman Dhayal Address of Applicant :School of Life & Basic Sciences, Jaipur National University, Jaipur-Agra Bypass, Near New RTO office, Jagatpura, Jaipur-302017, Rajasthan, India. Jaipur ----- -----</p> <p>5)Upasana Rani Address of Applicant :School of Life & Basic Sciences, Jaipur National University, Jaipur-Agra Bypass, Near New RTO office, Jagatpura, Jaipur-302017, Rajasthan, India. Jaipur ----- -----</p>
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(57) Abstract :

The present invention relates to a coconut de-husking device comprising, a platform 1 placed over a surface, plurality of motorized wheels 2 to provide movement to the housing, a disc 3 to be accessed by the user for placing a coconut, an imaging unit 4 for detecting dimensions of the coconut, a robotic arm 5 for picking and placing the coconut within a hollow cylindrical chamber 6, plurality of vertical sliders 9 configured with a robotic gripper 10 for gripping the husk portion of coconut, a tactile sensor 11 to determine hardness of the coconut, a telescopic rod 12 configured with a motorized cutter 13 for cutting the endocarp portion of coconut, a telescopic bar 14 configured with a chisel to aid in breaking the endocarp portion, a tray 15 to receive the withdrawal coconut that is accessed by the user to pick the coconut.

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