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(54) **PLANAR ROTARY TRANSFORMER**
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H02K 1/12 (2006.01)
H02K 3/28 (2006.01)
H02K 11/20 (2016.01)

(57) **ABSTRACT**

One example device includes a rotor platform that rotates about an axis of rotation. The device also includes a rotor coil comprising a first plurality of conductive loops disposed along a planar mounting surface of the rotor platform. The device also includes a stator platform and a stator coil comprising a second plurality of conductive loops disposed along a planar mounting surface of the stator platform. The rotor coil and the stator coil are coaxially arranged about the axis of rotation. The stator coil remains within a first predetermined distance to the rotor coil in response to rotation of the rotor platform. The device also includes a magnetic core extending along the axis of rotation and through the stator coil. The magnetic core remains within a second predetermined distance to the stator coil in response to rotation of the rotor platform.

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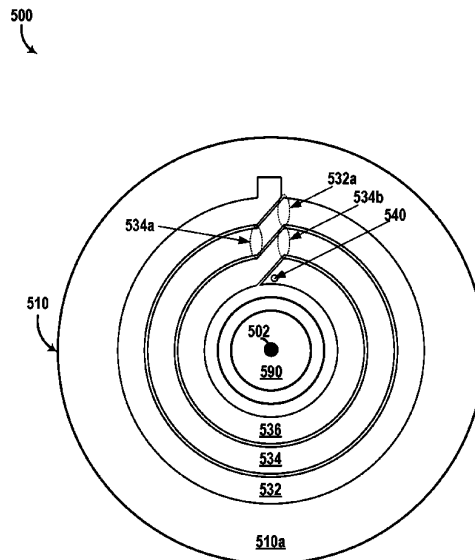
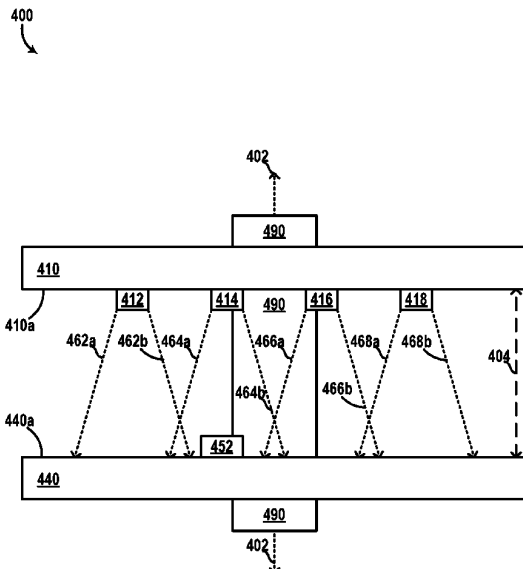
(58) **Field of Classification Search**
CPC H02K 3/26; H02K 23/54
See application file for complete search history.

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20 Claims, 6 Drawing Sheets



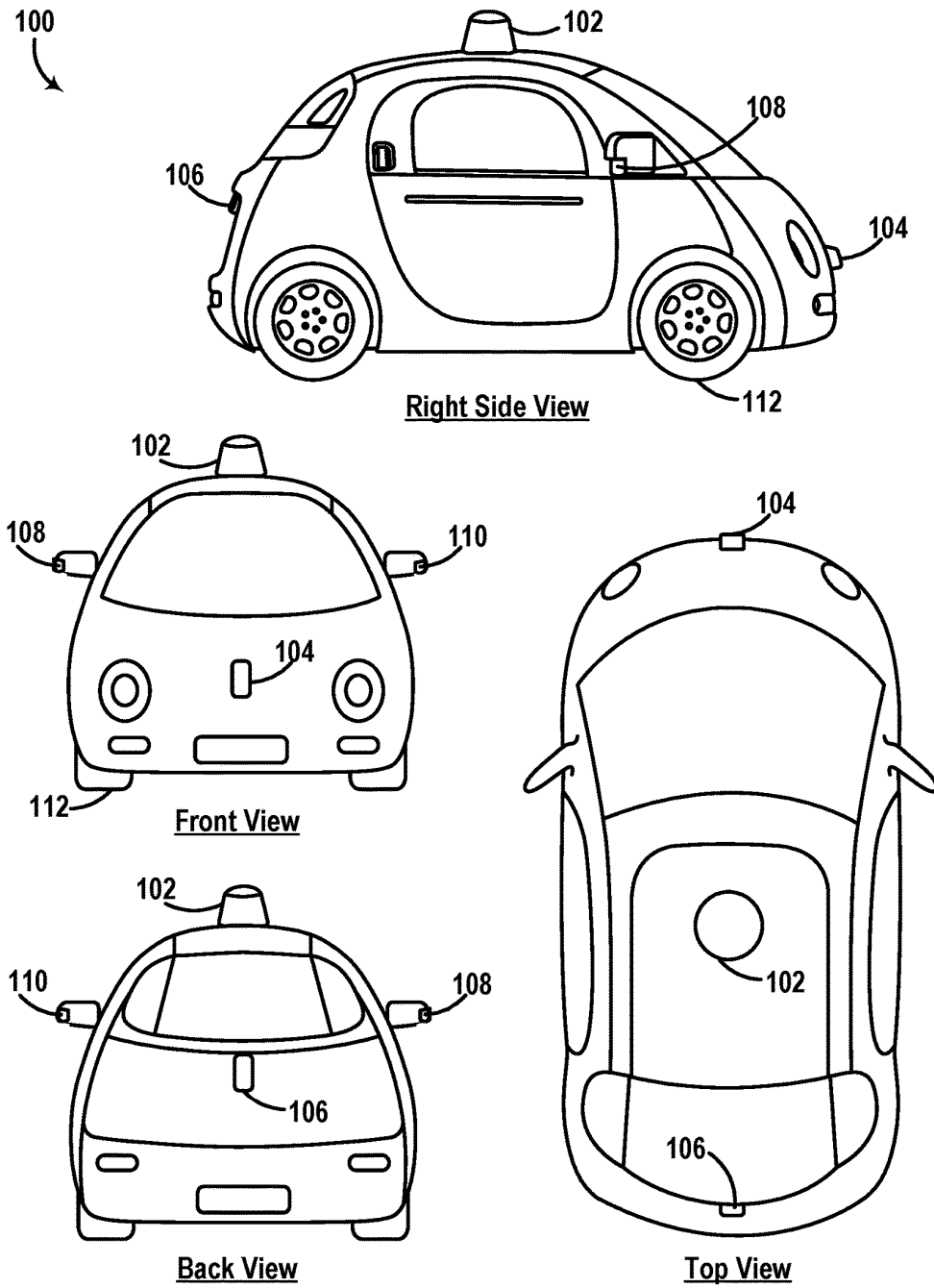


FIG. 1

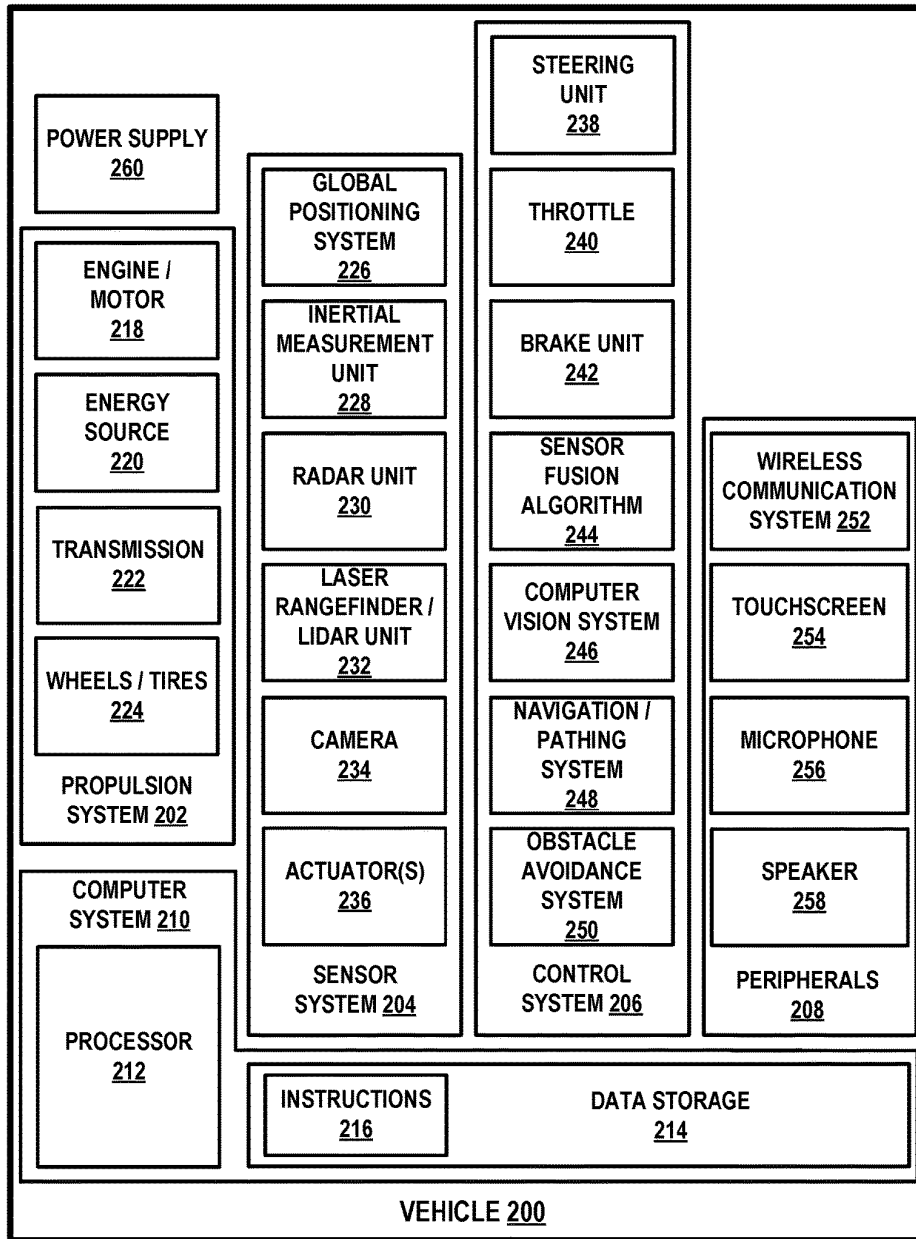


FIG. 2

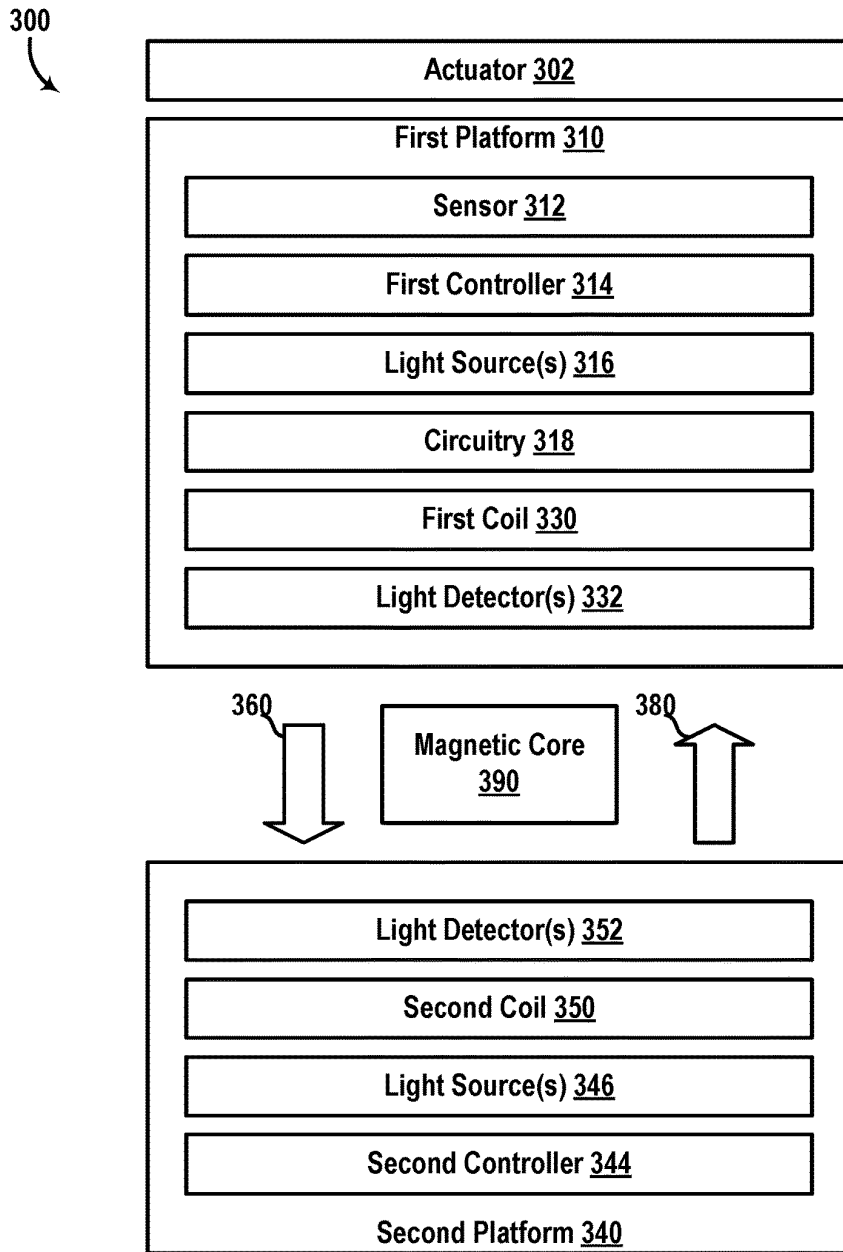


FIG. 3

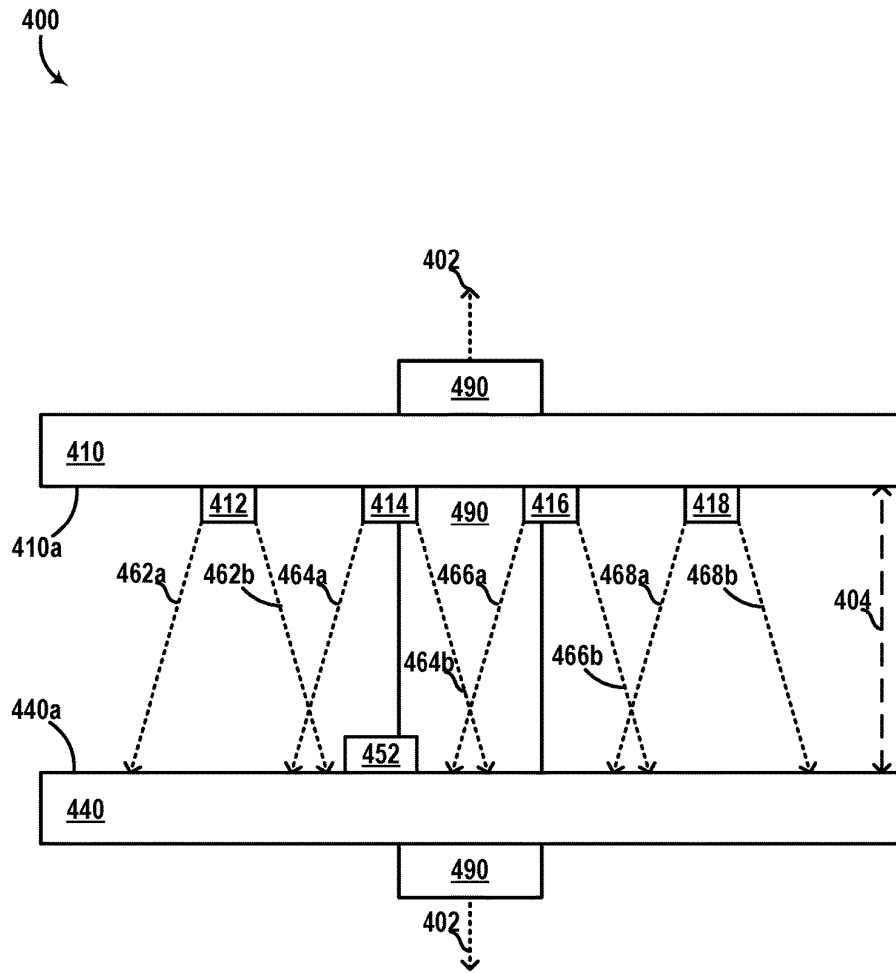


FIG. 4A

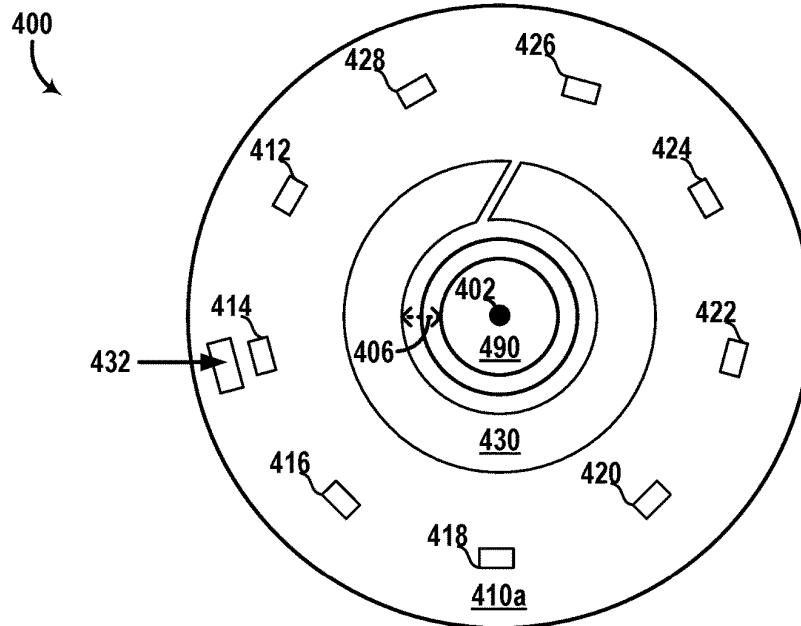


FIG. 4B

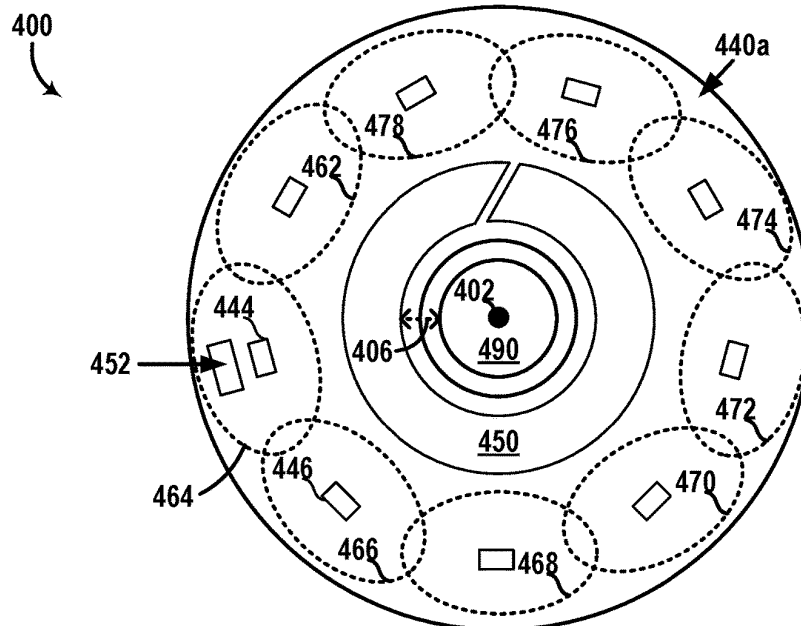


FIG. 4C

500
↙

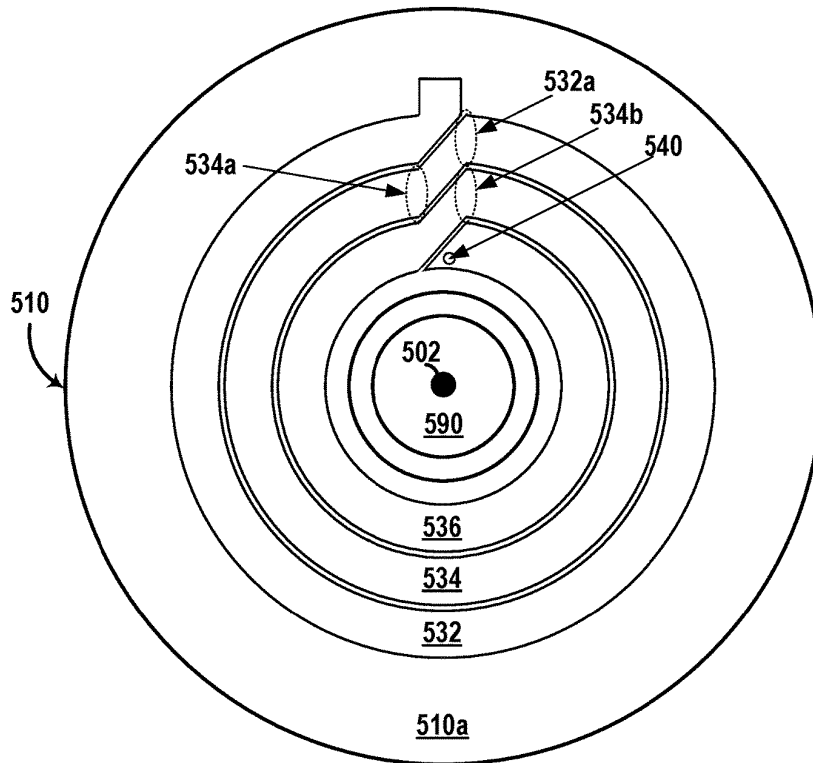


FIG. 5

PLANAR ROTARY TRANSFORMER**BACKGROUND**

Unless otherwise indicated herein, the materials described in this section are not prior art to the claims in this application and are not admitted to be prior art by inclusion in this section.

Rotary joint devices are often used for transmission of power and/or electrical signals between one structure and another structure in an electromechanical system that operates by causing a relative rotation between the two structures (e.g., stator and rotor). Example systems that employ rotary joint devices include remote sensing systems (e.g., RADARs, LIDARs, etc.) and robotic systems (e.g., for directing microphones, speakers, robotic components, etc.), among others.

SUMMARY

In one example, a device includes a rotor platform that rotates about an axis of rotation. The rotor platform includes a rotor planar mounting surface and a rotor coil. The rotor coil comprises a first plurality of conductive loops disposed along the rotor planar mounting surface. The device also includes a stator platform that includes a stator planar mounting surface. The device also includes a stator coil comprising a second plurality of conductive loops disposed along the stator planar mounting surface. The rotor coil and the stator coil are coaxially arranged about the axis of rotation. The stator coil remains within a first predetermined distance to the rotor coil in response to rotation of the rotor platform about the axis of rotation. The device also includes a magnetic core extending along the axis of rotation and through the stator coil. The magnetic core remains within a second predetermined distance to the stator coil in response to rotation of the rotor platform about the axis of rotation.

In another example, a device comprises a first platform having a first side and a second platform having a second side positioned to overlap the first side. The device also comprises an actuator that rotates the first platform relative to the second platform and about an axis of rotation of the first platform. The first side remains within a first predetermined distance to the second side in response to the actuator rotating the first platform. The device also comprises a first coil included in the first platform. The first coil comprises a first plurality of conductive loops in a coplanar arrangement substantially parallel to the first side. The device also comprises a second coil included in the second platform. The second coil comprises a second plurality of conductive loops in a coplanar arrangement substantially parallel to the second side. The device also comprises a magnetic core extending through the first coil and the second coil. A surface of the magnetic core adjacent to the first coil remains within a second predetermined distance to the first coil in response to the actuator rotating the first platform.

In yet another example, a device includes a rotor platform and a rotor printed circuit board (PCB) mounted to the rotor platform. The rotor platform rotates about an axis of rotation. The device also includes a stator platform and a stator PCB mounted to the stator platform. The rotor PCB remains at a first predetermined distance to the stator PCB in response to rotation of the rotor platform about the axis of rotation. The device also includes a rotor coil comprising one or more conductive loops patterned along a single layer of the rotor PCB. The device also includes a stator coil comprising one or more conductive loops patterned along a

single layer of the stator PCB. The rotor coil and the stator coil are concentrically arranged about the axis of rotation such that the rotor coil remains at least partially overlapping the stator coil responsive to rotation of the rotor platform about the axis of rotation. The device also includes a magnetic core extending through the rotor coil and the stator coil. A surface of the magnetic core remains at a second predetermined distance to the rotor coil and the stator coil responsive to rotation of the rotor coil about the axis of rotation.

These as well as other aspects, advantages, and alternatives, will become apparent to those of ordinary skill in the art by reading the following detailed description, with reference where appropriate to the accompanying figures.

BRIEF DESCRIPTION OF THE FIGURES

FIG. 1 illustrates a vehicle, according to an example embodiment.

FIG. 2 is a simplified block diagram of a vehicle, according to an example embodiment.

FIG. 3 is a simplified block diagram of a device that includes a rotary joint, according to an example embodiment.

FIG. 4A illustrates a side view of a device that includes a rotary joint, according to an example embodiment.

FIG. 4B illustrates a cross-section view of the device shown in FIG. 4A.

FIG. 4C illustrates another cross-section view of the device shown in FIG. 4A.

FIG. 5 illustrates a cross section view of another device that includes a rotary joint, according to an example embodiment.

DETAILED DESCRIPTION

The following detailed description describes various features and functions of the disclosed implementations with reference to the accompanying figures. In the figures, similar symbols identify similar components, unless context dictates otherwise. The illustrative implementations described herein are not meant to be limiting. It may be readily understood by those skilled in the art that certain aspects of the disclosed implementations can be arranged and combined in a wide variety of different configurations.

I. Overview

Within examples, a rotary joint device includes a rotary transformer configured to transmit power from a stator platform to a rotor platform of the device. The example rotary joint device includes two platforms arranged such that a first side of a first platform (one of the stator and rotor platforms) remains within a predetermined distance to a second side of a second platform (the other of the stator and rotor platforms) in response to a relative rotation between the two platforms. For instance, the two platforms may include circularly shaped disks arranged coaxially to maintain an overlap between the two respective sides (separated by the predetermined distance) in response to rotation of any of the two platforms about a common axis of the two platforms. Other configurations are possible as well.

In some implementations, the first platform may include a first coil comprising a first plurality of conductive loops in a coplanar arrangement substantially parallel to the first side of the first platform. For example, the first coil could be implemented as conductive traces or tracks patterned along

a first layer of a circuit board (e.g., PCB, etc.) in the first platform. In some examples, the first coil may also include another plurality of conductive loops coupled to the first plurality of loops. For example, the circuit board may include multiple layers, and the other plurality of conductive loops could be implemented as conductive traces or tracks patterned along a second layer of the circuit board. In these examples, the device may also include an electrical contact (e.g., a via between the two circuit board layers) that electrically couples a single conductive loop in the first layer to an adjacent overlapping conductive loop in the second layer.

Additionally, in these implementations, the second platform may include a second coil comprising a second plurality of conductive loops in a coplanar arrangement substantially parallel to the second side of the second platform. For instance, the first coil and the second coil can be coaxially arranged about an axis of rotation of the first platform (or the second platform) such that the two coils remain overlapping at the predetermined distance to one another in response to a relative rotation between the two platforms.

Additionally, in some implementations, the device may also include a magnetic core (e.g., transformer core, ferrite material, etc.) that extends through the first coil and/or the second coil. A surface of the magnetic core adjacent to the first coil (and/or the second coil) may be configured to remain within a second predetermined distance to the first coil in response to a relative rotation between the two platforms. For example, the magnetic core may have a cylindrically shaped outer surface having a cylinder axis aligned with the axis of rotation. In this example, if the first platform rotates about the axis, then the outer surface of the magnetic core may remain separated by the second predetermined distance to the two coils.

With this arrangement, for example, the first coil and the second coil could form a rotary transformer for transmitting power from the second platform (e.g., stator) to the first platform (e.g., rotor), while the first platform is rotating relative to the second platform. Further, for example, a winding or coil design can be integrated directly onto a PCB that also includes or mounts other components such as optical communication components (e.g., light sources, photodetectors, etc.), sensors, etc. By doing so, for instance, the device may improve assembly efficiency for various rotary joint implementations. Further, for instance, the magnetic core could facilitate concentrating and/or increasing the magnetic flux between the two coils by positioning the outer surface of the core at a relatively small distance relative to the coils, while also maintaining a sufficiently larger distance between the two platforms to allow divergence of light used for optical communication between the two platforms. For example, a cross-sectional area of the stator platform that is illuminated by a light source in the rotor platform may increase as the distance between the two platforms increases. Thus, in some examples, the device may include optical communication components (e.g., light sources, etc.) mounted on a same platform (e.g., PCB) as the transformer coils.

Other example arrangements, configurations, and operations are possible as well and are described in greater detail within exemplary implementations herein.

II. Example Electromechanical Systems and Devices

Systems and devices in which example embodiments may be implemented will now be described in greater detail. In

general, the embodiments disclosed herein can be used with any electromechanical system that includes a moveable component. An example system can provide for transmission of power and/or signals between the moveable component and other parts of the system. Illustrative embodiments described herein include vehicles that have moveable components such as sensors and wheels that communicate with other components of the vehicle and/or with one another. However, an example electromechanical system may also be implemented in or take the form of other devices, such as sensing platforms (e.g., RADAR platforms, LIDAR platforms, directional sensing platforms, etc.), robotic devices, industrial systems (e.g., assembly lines, etc.), medical devices (e.g., medical imaging devices, etc.), or mobile communication systems, among others. The term “vehicle” is broadly construed herein to cover any moving object, including, for instance, an aerial vehicle, watercraft, spacecraft, a car, a truck, a van, a semi-trailer truck, a motorcycle, a golf cart, an off-road vehicle, a warehouse transport vehicle, a farm vehicle, or a carrier that rides on a track (e.g., roller coaster, trolley, tram, train car, etc.), among other examples.

FIG. 1 illustrates a vehicle 100, according to an example embodiment. In particular, FIG. 1 shows a Right Side View, Front View, Back View, and Top View of the vehicle 100. Although vehicle 100 is illustrated in FIG. 1 as a car, as noted above, other types of vehicles are possible as well. Furthermore, although vehicle 100 can be configured to operate autonomously, the embodiments described herein are also applicable to vehicles that are not configured to operate autonomously or that are configured to operate semi-autonomously. Thus, vehicle 100 is not meant to be limiting. As shown, vehicle 100 includes five sensor units 102, 104, 106, 108, and 110, and four wheels, exemplified by wheel 112.

In some embodiments, sensor units 102-110 may include any combination of sensors, such as global positioning system sensors, inertial measurement units, radio detection and ranging (RADAR) units, cameras, laser rangefinders, light detection and ranging (LIDAR) units, or acoustic sensors, among other possibilities.

As shown, sensor unit 102 is mounted to a top side of the vehicle 100 opposite to a bottom side of the vehicle 100 where the wheel 112 is mounted. Further, sensor units 104-110 are respectively mounted to respective sides of vehicle 100 other than the top side. As shown, sensor unit 104 is positioned at a front side of vehicle 100, sensor 106 is positioned at a back side of vehicle 100, the sensor unit 108 is positioned at a right side of vehicle 100, and sensor unit 110 is positioned at a left side of vehicle 100.

Although sensor units 102-110 are shown to be mounted in particular locations on vehicle 100, in some embodiments, sensor units 102-110 can be mounted in other locations, either inside or outside vehicle 100. For example, although sensor unit 108 as shown is mounted to a rear-view mirror of vehicle 100, sensor unit 108 may alternatively be positioned in another location along the right side of vehicle 100. Further, while five sensor units are shown, in some embodiments more or fewer sensor units may be included in vehicle 100. However, for the sake of example, sensor units 102-110 are positioned as shown.

In some embodiments, one or more of sensor units 102-110 may include one or more movable mounts on which the sensors can be movably mounted. A movable mount may include, for example, a rotating platform. Alternatively or additionally, a movable mount may include a tilting platform. Sensors mounted on a tilting platform could be tilted

within a given range of angles and/or azimuths, for example. A movable mount may take other forms as well.

In some embodiments, one or more of sensor units **102-110** may include one or more actuators configured to adjust a position and/or orientation of sensors in the sensor unit by moving the sensors and/or movable mounts. Example actuators include motors, pneumatic actuators, hydraulic pistons, relays, solenoids, and piezoelectric actuators, among others.

As shown, vehicle **100** includes one or more wheels such as wheel **112** that are configured to rotate to cause the vehicle to travel along a driving surface. In some embodiments, wheel **112** may include at least one tire coupled to a rim of wheel **112**. To this end, wheel **112** may include any combination of metal and rubber, or a combination of other materials. Vehicle **100** may include one or more other components in addition to or instead of those shown.

FIG. 2 is a simplified block diagram of a vehicle **200**, according to an example embodiment. Vehicle **200** may be similar to vehicle **100**, for example. As shown, vehicle **200** includes a propulsion system **202**, a sensor system **204**, a control system **206**, peripherals **208**, and a computer system **210**. In other embodiments, vehicle **200** may include more, fewer, or different systems, and each system may include more, fewer, or different components. Further, the systems and components shown may be combined or divided in any number of ways.

Propulsion system **202** may be configured to provide powered motion for the vehicle **200**. As shown, propulsion system **202** includes an engine/motor **218**, an energy source **220**, a transmission **222**, and wheels/tires **224**.

Engine/motor **218** may be or include any combination of an internal combustion engine, an electric motor, a steam engine, and a Stirling engine. Other motors and engines are possible as well. In some embodiments, propulsion system **202** may include multiple types of engines and/or motors. For instance, a gas-electric hybrid car may include a gasoline engine and an electric motor. Other examples are possible.

Energy source **220** may be a source of energy that powers the engine/motor **218** in full or in part. That is, engine/motor **218** may be configured to convert energy source **220** into mechanical energy. Examples of energy sources **220** include gasoline, diesel, propane, other compressed gas-based fuels, ethanol, solar panels, batteries, and other sources of electrical power. Energy source(s) **220** may additionally or alternatively include any combination of fuel tanks, batteries, capacitors, and/or flywheels. In some embodiments, energy source **220** may provide energy for other systems of vehicle **200** as well.

Transmission **222** may be configured to transmit mechanical power from engine/motor **218** to wheels/tires **224**. To this end, transmission **222** may include a gearbox, clutch, differential, drive shafts, and/or other elements. In embodiments where transmission **222** includes drive shafts, the drive shafts may include one or more axles that are configured to be coupled to wheels/tires **224**.

Wheels/tires **224** of vehicle **200** may be configured in various formats, including a unicycle, bicycle/motorcycle, tricycle, or car/truck four-wheel format. Other wheel/tire formats are possible as well, such as those including six or more wheels. In any case, wheels/tires **224** may be configured to rotate differentially with respect to other wheels/tires **224**. In some embodiments, wheels/tires **224** may include at least one wheel that is fixedly attached to transmission **222** and at least one tire coupled to a rim of the wheel that could make contact with a driving surface. Wheels/tires **224** may

include any combination of metal and rubber, or combination of other materials. Propulsion system **202** may additionally or alternatively include components other than those shown.

Sensor system **204** may include any number of sensors configured to sense information about vehicle **200** and/or an environment in which vehicle **200** is located, as well as one or more actuators **236** configured to modify a position and/or orientation of the sensors. As shown, sensor system **204** includes a Global Positioning System (GPS) **226**, an inertial measurement unit (IMU) **228**, a RADAR unit **230**, a laser rangefinder and/or LIDAR unit **232**, and a camera **234**. Sensor system **204** may include additional sensors as well, including, for example, sensors that monitor internal systems of vehicle **200** (e.g., an O₂ monitor, a fuel gauge, an engine oil temperature, etc.). Other sensors are possible as well. In some examples, sensor system **204** may be implemented as multiple sensor units each mounted to the vehicle in a respective position (e.g., top side, bottom side, front side, back side, right side, left side, etc.).

GPS **226** may include any sensor (e.g., location sensor) configured to estimate a geographic location of vehicle **200**. To this end, for example, GPS **226** may include a transceiver configured to estimate a position of vehicle **200** with respect to the Earth. IMU **228** may include any combination of direction sensors configured to sense position and orientation changes of the vehicle **200** based on inertial acceleration. Example IMU sensors include accelerometers, gyroscopes, other direction sensors, etc. RADAR unit **230** may include any sensor configured to sense objects in an environment in which vehicle **200** is located using radio signals. In some embodiments, in addition to sensing the objects, RADAR unit **230** may be configured to sense the speed and/or heading of the objects.

Laser rangefinder or LIDAR unit **232** may include any sensor configured to sense objects in the environment in which vehicle **200** is located using light. In particular, laser rangefinder or LIDAR unit **232** may include one or more light sources configured to emit one or more beams of light and a detector configured to detect reflections of the one or more beams of light. Laser rangefinder or LIDAR **232** may be configured to operate in a coherent (e.g., using heterodyne detection) or an incoherent detection mode. In some examples, LIDAR unit **232** may include multiple LIDARs, with each LIDAR having a particular position and/or configuration suitable for scanning a particular region of an environment around vehicle **200**.

Camera **234** may include any camera (e.g., still camera, video camera, etc.) that can capture images of an environment of vehicle **200**. Actuator(s) **236** may include any type of actuator configured to adjust a position, orientation, and/or pointing direction of one or more of the sensors of system **204**. Example actuators include motors, pneumatic actuators, hydraulic pistons, relays, solenoids, and piezoelectric actuators, among other examples. Sensor system **204** may additionally or alternatively include components other than those shown.

Control system **206** may be configured to control operation of vehicle **200** and/or components thereof. To this end, control system **206** may include a steering unit **238**, a throttle **240**, a brake unit **242**, a sensor fusion algorithm **244**, a computer vision system **246**, a navigation or pathing system **248**, and an obstacle avoidance system **250**.

Steering unit **238** may be any combination of mechanisms configured to adjust the heading of vehicle **200**. Throttle **240** may be any combination of mechanisms configured to control the operating speed of engine/motor **218** and, in turn,

the speed of vehicle **200**. Brake unit **242** may be any combination of mechanisms configured to decelerate vehicle **200**. For example, brake unit **242** may use friction to slow wheels/tires **224**. In some examples, brake unit **242** may also convert kinetic energy of wheels/tires **224** to an electric current.

Sensor fusion algorithm **244** may be an algorithm (or a computer program product storing an algorithm) configured to accept data from sensor system **204** as an input. The data may include, for example, data representing information sensed at the sensors of sensor system **204**. Sensor fusion algorithm **244** may include, for example, a Kalman filter, a Bayesian network, an algorithm for some of the functions of the methods herein, or any other algorithm. Sensor fusion algorithm **244** may further be configured to provide various assessments based on the data from sensor system **204**, including, for example, evaluations of individual objects and/or features in the environment in which vehicle **100** is located, evaluations of particular situations, and/or evaluations of possible impacts based on particular situations.

Computer vision system **246** may be any system configured to process and analyze images captured by camera **234** in order to identify objects and/or features in the environment in which vehicle **200** is located, including, for example, traffic signals and obstacles. To this end, computer vision system **246** may use an object recognition algorithm, a Structure from Motion (SFM) algorithm, video tracking, or other computer vision techniques. In some embodiments, computer vision system **246** may additionally be configured to map the environment, track objects, estimate the speed of objects, etc.

Navigation and pathing system **248** may be any system configured to determine a driving path for vehicle **200**. Navigation and pathing system **248** may additionally be configured to update the driving path dynamically while vehicle **200** is in operation. In some embodiments, navigation and pathing system **248** may be configured to incorporate data from sensor fusion algorithm **244**, GPS **226**, LIDAR unit **232**, and/or one or more predetermined maps of the environment of vehicle **200**, so as to determine a driving path for vehicle **200**. Obstacle avoidance system **250** may be any system configured to identify, evaluate, and avoid or otherwise negotiate obstacles in the environment in which vehicle **200** is located. Control system **206** may additionally or alternatively include components other than those shown.

Peripherals **208** (e.g., input interface, output interface, etc.) may be configured to allow vehicle **200** to interact with external sensors, other vehicles, external computing devices, and/or a user. To this end, peripherals **208** may include, for example, a wireless communication system **252**, a touchscreen **254**, a microphone **256**, and/or a speaker **258**.

Wireless communication system **252** may be any system configured to wirelessly couple to one or more other vehicles, sensors, or other entities, either directly or via a communication network. To this end, wireless communication system **252** may include an antenna and a chipset for communicating with the other vehicles, sensors, servers, or other entities either directly or via a communication network. Chipset or wireless communication system **252** in general may be arranged to communicate according to one or more types of wireless communication (e.g., protocols) such as Bluetooth, communication protocols described in IEEE 802.11 (including any IEEE 802.11 revisions), cellular technology (such as GSM, CDMA, UMTS, EV-DO, WiMAX, or LTE), Zigbee, dedicated short range communications (DSRC), and radio frequency identification

(RFID) communications, among other possibilities. Wireless communication system **252** may take other forms as well.

Touchscreen **254** may be used by a user as an input interface to input commands to vehicle **200**. To this end, touchscreen **254** may be configured to sense at least one of a position and a movement of a user's finger via capacitive sensing, resistance sensing, or a surface acoustic wave process, among other possibilities. Touchscreen **254** may be capable of sensing finger movement in a direction parallel or planar to the touchscreen surface, in a direction normal to the touchscreen surface, or both, and may also be capable of sensing a level of pressure applied to the touchscreen surface. Touchscreen **254** may be formed of one or more translucent or transparent insulating layers and one or more translucent or transparent conducting layers. Touchscreen **254** may take other forms as well.

Microphone **256** may be configured to receive audio (e.g., a voice command or other audio input) from a user of vehicle **200**. Similarly, speakers **258** may be configured to output audio to the user of vehicle **200**. Peripherals **208** may additionally or alternatively include components other than those shown.

Computer system **210** may be configured to transmit data to, receive data from, interact with, and/or control one or more of propulsion system **202**, sensor system **204**, control system **206**, and peripherals **208**. To this end, computer system **210** may be communicatively linked to one or more of propulsion system **202**, sensor system **204**, control system **206**, and peripherals **208** by a system bus, network, and/or other connection mechanism (not shown).

In one example, computer system **210** may be configured to control operation of transmission **222** to improve fuel efficiency. As another example, computer system **210** may be configured to cause camera **234** to capture images of the environment. As yet another example, computer system **210** may be configured to store and execute instructions corresponding to sensor fusion algorithm **244**. Other examples are possible as well.

As shown, computer system **210** includes processor **212** and data storage **214**. Processor **212** may comprise one or more general-purpose processors and/or one or more special-purpose processors. To the extent processor **212** includes more than one processor, such processors could work separately or in combination. Data storage **214**, in turn, may comprise one or more volatile and/or one or more non-volatile storage components, such as optical, magnetic, and/or organic storage among other possibilities, and data storage **214** may be integrated in whole or in part with processor **212**.

In some embodiments, data storage **214** contains instructions **216** (e.g., program logic) executable by processor **212** to execute various vehicle functions. Data storage **214** may contain additional instructions as well, including instructions to transmit data to, receive data from, interact with, and/or control one or more of propulsion system **202**, sensor system **204**, control system **206**, and/or peripherals **208**. In some embodiments, data storage **214** also contains calibration data for one or more of the sensors in sensor system **204**. For example, the calibration data may include a mapping between previously obtained sensor measurements and one or more predetermined inputs to the sensors. Computer system **210** may additionally or alternatively include components other than those shown.

Power supply **260** may be configured to provide power to some or all of the components of vehicle **200**. To this end, power supply **260** may include, for example, a rechargeable

lithium-ion or lead-acid battery. In some embodiments, one or more banks of batteries could be configured to provide electrical power. Other power supply materials and configurations are possible as well. In some embodiments, power supply 260 and energy source 220 may be implemented together as one component, as in some all-electric cars for instance.

In some embodiments, vehicle 200 may include one or more elements in addition to or instead of those shown. For example, vehicle 200 may include one or more additional interfaces and/or power supplies. Other additional components are possible as well. In such embodiments, data storage 214 may further include instructions executable by processor 212 to control and/or communicate with the additional components. Still further, while each of the components and systems are shown to be integrated in vehicle 200, in some embodiments, one or more components or systems can be removably mounted on or otherwise connected (mechanically or electrically) to vehicle 200 using wired or wireless connections.

III. Example Rotary Joint Configurations

Within examples, a rotary joint may be configured as an interface between two structures of an electromechanical system, in which one or both of the two structures is configured to rotate or otherwise move relative to the other structure. To that end, in some implementations, a portion of the rotary joint (e.g., rotor) may be coupled to one structure of the example system and another portion (e.g., stator) may be coupled to the other structure of the example system. Additionally or alternatively, in some implementations, the rotary joint may be included within a structure arranged between two structures that rotate (or move) with respect to one another. For instance, an example rotary joint could be disposed in a robotic joint that couples two robotic links. Other implementations are possible as well.

FIG. 3 is a simplified block diagram of a device 300 that includes a rotary joint, according to an example embodiment. For example, device 300 can be used as an interface between moveable components of an electromechanical system, such as any of vehicles 100, 200, and/or any other electromechanical system. Thus, for instance, device 300 can be physically implemented as a rotary joint that facilitates power transmission between two moveable components of the system (or subsystem), such as a rotating platform that mounts sensors included in sensor units 102, 104, 106, 108, 110, sensor system 204, among other examples. As shown, device 300 includes an actuator 302, a first platform 310, a second platform 340, and a magnetic core 390.

Actuator 302 may be similar to the actuator(s) 236 of the vehicle 200, for example. To that end, actuator 302 may be configured to cause a relative rotation between first platform 310 (or one or more components thereof) and second platform 340 (or one or more components thereof). For instance, actuator 302 may be coupled to one or both of platforms 310, 340 (or one or more components thereof) to cause the relative rotation.

First platform 310 may comprise or may be coupled to a sensor mounting platform, and may be configured as a rotor or a stator in a rotary joint configuration. For example, actuator 302 may be configured to rotate platform 310 relative to platform 340 and about an axis of rotation of platform 310 (e.g., rotor axis, etc.). Alternatively or additionally, for example, actuator 302 could rotate platform 340 relative platform 310 about an axis of rotation of platform

340. Thus, within various examples, platform 310 can be configured as a rotating platform (e.g., rotor) or a stationary platform (e.g., stator) in a rotary joint configuration.

As shown, platform 310 includes a sensor 312, a first controller 314, one or more light sources 316, circuitry 318, a first coil 330, and one or more light detectors 332. In some examples, platform 310 may comprise any solid material suitable for supporting and/or mounting various components of platform 310. For instance, platform 310 may include a printed circuit board (PCB) that mounts light source(s) 316, coil 330, light detector(s) 332, and/or other components of platform 310. The PCB in this instance can be positioned such that the mounted components are along a side of platform 310 facing or opposite to a corresponding side of platform 340. With this arrangement, for instance, light source(s) 316 can emit light 360 for propagation toward second platform 340 and light detector(s) 332 can receive light 380 propagating from second platform 340 toward first platform 310.

Sensor 312 may include any combination of sensors mounted to first platform 310, such as one or more sensors of sensor system 204, one or more of the sensors included in vehicle 100, and/or any other sensor that can be mounted on platform 310. A non-exhaustive list of example sensors may include direction sensors (e.g., gyroscopes), remote sensing devices (e.g., RADARs, LIDARs, etc.), sound sensors (e.g., microphones), among others.

First controller 314 may be configured to operate one or more of the components of first platform 310. To that end, controller 314 may include any combination of general-purpose processors, special-purpose-processors, data storage, logic circuitry, and/or any other circuitry configured to operate one or more components of device 300. In one implementation, similarly to computing system 210, controller 314 includes one or more processors (e.g., processor 212) that execute instructions (e.g., instructions 216) stored in data storage (e.g., data storage 214) to operate sensor 312, light source(s) 316, etc. In another implementation, controller 314 alternatively or additionally includes circuitry wired to perform one or more of the functions and processes described herein for operating one or more of the components of device 300. In one example, controller 314 can be configured to receive sensor data collected by sensor 312, and to provide a modulated electrical signal indicative of the sensor data to light source(s) 316. For instance, the sensor data may indicate a measured orientation of sensor 312, a scan of a surrounding environment, detected sounds, and/or any other sensor output of sensor 312.

Light source(s) 316 may include one or more light sources arranged to emit or otherwise provide light beam(s) 360 incident on platform 340. To that end, light source(s) 316 may include laser diodes, light emitting diodes (LEDs), vertical cavity surface emitting lasers (VCSEL), organic light emitting diodes (OLEDs), polymer light emitting diodes (PLED), light emitting polymers (LEP), liquid crystal displays (LCD), microelectromechanical systems (MEMS), discharge light sources (e.g., fluorescent lamp, etc.), incandescent light sources (e.g., halogen lamp, filament lamp, etc.), combustion light sources, among other examples.

In a first implementation, light source(s) 316 comprise a plurality of light sources mounted in platform 310 in a substantially circular arrangement around an axis of rotation of the platform 310. The plurality of light sources may emit a plurality of light beams that diverge to form a ring-shaped light beam incident on platform 340 (and/or a component thereof). For example, platforms 310 and 340 can be positioned at a predetermined distance to one another. The

predetermined distance can be selected according to the respective distances between adjacent light sources and/or beam divergences of the adjacent light sources. A beam divergence may be an angular measure of the increase in beam diameter or radius relative to a distance of propagation of light beam(s) **360**. Thus, for instance, the predetermined distance can be selected to be greater than or equal to a distance at which adjacent light beams of light **360** intersect. In a second implementation, light source(s) **316** comprise a single ring-shaped light source. For instance, a single light source **316** can be implemented as an OLED patterned on a PCB layer in the shape of a ring. In a third implementation, light source(s) **316** comprise one or more light sources coupled to one or more optical elements (e.g., light diffusers, lens, filters, etc.) that are arranged to redirect or focus light beam(s) **360** to form a ring-shaped light beam.

Circuitry **318** may include any combination of wiring, conductive material, capacitors, resistors, amplifiers, filters, comparators, voltage regulators, controllers, and/or any other circuitry arranged to electrically couple one or more components of platform **310**. In some examples, circuitry **318** could be arranged to condition electrical communication and power signals between two or more components of platform **310**. For instance, circuitry **318** may include one or more voltage regulators that condition electrical power received via transformer coil **330** to power sensor **312**, controller **314**, light source(s) **316**, and/or detector(s) **332**, according to respective voltage inputs permitted by the respective components of platform **310**.

First coil **330** may comprise one or more conductive loops concentrically arranged about an axis of rotation of platform **310** (and/or **340**). In one implementation, first coil **330** may comprise a plurality of conductive loops in a coplanar arrangement around the axis of rotation. For instance, coil **330** can be implemented as a plurality of conductive tracks (e.g., copper, etc.) patterned along a single layer of a circuit board (e.g., PCB) that also mounts light source(s) **316**. The PCB, for instance, may also include conductive tracks in the single layer that are coupled to light source(s) **316**, detector(s) **332**, etc. With this arrangement, for instance, assembly cost, maintenance cost, and space improvements can be achieved by implementing platform **310** (or a portion thereof) as a single mounting platform (e.g., circuit board) that includes a mounting surface for light source(s) **316**, light detector(s) **332**, etc., as well as coil **330** patterned along the same circuit board layer that includes conductive tracks (e.g., circuitry **318**, etc.) coupling the various components of platform **310**. Thus, in some examples, such PCB of platform **310** can be a replaceable, cost-effective, distance-calibrated component that is suitable for relatively small rotary joint implementations.

In some implementations, first coil **330** may also comprise a second plurality of conductive loops in another coplanar arrangement that is parallel to the coplanar arrangement of the (first) plurality of conductive loops. For example, coil **330** may include the second plurality of conductive loops patterned along a second layer of the circuit board (e.g., along an opposite side of a two-layer PCB, or along a middle layer of a multi-layer PCB, etc.). In this example, the conductive loops in each layer can be electrically coupled via an electrical contact (e.g., "via") that extends between one of the conductive loops in one layer and an adjacent (e.g., overlapping) conductive loop in the second layer. With this arrangement, for instance, the number of loops (e.g., transformer windings) in first coil **330** can be increased to allow a greater amount of power transmission between first coil **330** and a corresponding second coil

in second platform **340**. Additionally or alternatively, with this arrangement for instance, incorporating multiple loops (e.g., transformer windings) may allow device **300** to transform a voltage level of an induced electrical current flowing through coil **330** relative to a driving electrical current flowing through the corresponding second coil. Further, with this arrangement for instance, device **300** may allow an optimal use of copper (or other conductive material) included in a cross sectional area of platform **310** (e.g., circuit board, etc.) surrounding the axis of rotation of platform **310** to increase the amount and efficiency of power transmission between platforms **310** and **340**.

Detector(s) **332** may comprise one or more light detectors (e.g., photodetectors) that convert light **380** into a signal (e.g., a voltage and/or current signal) that can be measured via controller **314**. To that end, light detector(s) or photodetector(s) **332** may include any combination of light sensors such as photodiodes, photoemission sensors, photoelectric sensors, photovoltaic sensors, thermal sensors, polarization sensors, photochemical sensors, among others. In some examples, detector(s) **332** may be configured to detect light at a particular wavelength or within a particular bandwidth associated with light **380**. Thus, for example, device **300** can be less sensitive to noise (e.g., environmental light) that is not within a predetermined wavelength range associated with light **380**.

In some implementations, detector(s) **332** remains at least partially overlapping light beam **380** in response to actuator **302** rotating platform **310** relative to platform **340**. For example, light beam **380** may have a ring shape or other continuous shape (e.g., a combination of adjacent light beams that intersect at or prior to arrival at platform **310**, etc.) extending around an axis of rotation of platform **310**. In this example, detector **332** can be positioned at a particular distance to the axis of rotation such that detector **332** overlaps (at least partially) light beam(s) **380** at any orientation of platform **310** about the axis of rotation. Thus, for example, where light beam **380** is a modulated light beam (e.g., sequence of light pulses, etc.) indicating wirelessly transmitted data from platform **340**, detector **332** can continue to detect the modulated light beam even as platform **310** rotates relative to platform **340**.

Platform **340** may be configured as a rotor or a stator, similarly to the various configurations described for platform **310**. As shown, platform **340** includes a second controller **344**, one or more light sources **346**, a second coil **350**, and one or more light detectors **352**. In some examples, platform **340** may also include an orientation sensor (not shown), such as an encoder, range sensor, etc., that provides a measure of an orientation of platform **310** relative to platform **340** (e.g., about an axis of rotation of platform **310**).

Controller **344** can have various physical implementations (e.g., processors, logic circuitry, data storage, etc.) similarly to controller **314**, for example. Further, controller **344** can operate light source(s) **346** to transmit a modulated light signal **380** indicating a transmission of data or instructions similarly to, respectively, controller **314**, light source(s) **316**, and light signal **360**. For instance, controller **344** can provide a modulated electrical signal to cause light source(s) **346** to provide modulated light **380** indicating instructions for operating sensor **312** and/or any other component (e.g., actuator **302**, etc.) coupled to platform **310**. Further, for instance, controller **344** can receive a modulated electrical signal from detector(s) **352** indicating modulated light **360**. To that end, for instance, modulated light **360** may

indicate sensor data collected by sensor 312 and transmitted, via light 360, to platform 340.

Further, similarly to first coil 330, second coil 350 may include one or more conductive loops concentrically arranged in one or more coplanar arrangements around an axis of rotation of platform 310 (and/or 340). Further, for example, coil 350 can be arranged to overlap opposite to coil 330 at the predetermined distance between platforms 310 and 340. In one implementation, device 300 may cause an electrical current to flow through coil 350. As a result, coil 350 may generate a magnetic field extending through a center of coil 350 toward a center of coil 330. A portion of the magnetic field extending through coil 330 may then induce an electrical current flowing through coil 330, which can be harvested to power various components (e.g., sensor 312, light source(s) 316, etc.) coupled to platform 310, for instance.

Accordingly, light source(s) 346, coil 350, and detector(s) 352 can be configured, physically implemented, and/or arranged, etc., in a similar manner to, respectively, light source(s) 316, coil 330, and detector(s) 332. By way of example, a circuit board implementation of platform 340 can be substantially similar to a circuit board implementation of platform 310. As a result, assembly and maintenance cost improvements for device 300 can be achieved by physically implementing a replaceable circuit board that can be used for either platform.

However, in some examples, one or more components of platform 340 can have different characteristics than corresponding components of platform 310. In one example, light source(s) 346 can be implemented to include a different number of light sources or may emit light 380 having different wavelengths, among other possibilities (e.g., different phases, polarizations, intensities, etc.). In another example, transformer coil 330 may include a different number of conductive loops than transformer coil 350. Other examples are possible.

As noted above, in some implementations, platform 310 is positioned at a first predetermined distance to platform 340 to facilitate formation of ring-shaped light beam 360 incident on platform 340 for detection by detector 352. By way of example, where light sources 316 comprise a plurality of light sources in a circular arrangement, the first predetermined distance may be greater than or equal to a given distance at which adjacent diverging light beams of light 360 intersect to form ring-shaped light beam 360 prior to or at arrival of light beam 360 to a surface of platform 340. Thus, in this example, detector(s) 352 may remain at least partially overlapping light 360 at any orientation of platform 310 around its axis of rotation. Further, as the first predetermined distance increases, a cross-sectional area of diverging ring-shaped light beam 360 incident on platform 340 may increase, which may thereby increase an availability of positions along a mounting surface of platform 340 for placement of detector(s) 352 to remain at least partially overlapping light 360 in response to rotation of platform 310.

However, as the first predetermined distance between platforms 310 and 340 increases, the power transmission efficiency between coils 330 and 350 may decrease due to divergence of the magnetic field generated by coil 350. For instance, as the first predetermined distance increases, a larger portion of the generated magnetic field may diverge away from the center of coil 330. As a result, a smaller amount of power may be transmitted as electrical current flowing through coil 330 due to a smaller portion of the

generated magnetic field (e.g., lower magnetic flux density, etc.) extending through the center of coil 330.

Accordingly, device 300 can optionally include magnetic core 390 configured to guide a magnetic field generated by coil 350 through coil 330. To that end, core 390 can be formed from a ferromagnetic material such as iron, ferromagnetic compounds, ferrites, etc. For example, core 390 may comprise a material having a high magnetic permeability relative to surrounding air to cause a relatively larger portion of magnetic field lines generated by coil 350 to be concentrated inside core 390. Further, in some implementations, core 390 can be arranged to extend through coil 330 and/or 350. For instance, core 390 can be implemented as a cylindrical structure extending along the axis of rotation of platform 310 and through one or more of coils 330, 350. With this arrangement, for instance, a surface of magnetic core 390 may remain within a second predetermined distance to coil 330 and/or 350 in response to a rotation of platform 310 about the axis of rotation. Further, for example, the second predetermined distance can be less than the first predetermined distance between the two platforms 310 and 340. Thus, with this arrangement for instance, device 300 can mitigate the effect of the larger first predetermined distance between platforms 310 and 340 by guiding the generated magnetic field (through core 390) toward coil 330.

In some implementations, device 300 may include fewer components than those shown. For example, device 300 can be implemented without light source(s) 346, detector(s) 352, etc. Further, in some implementations, device 300 may include one or more components in addition to or instead of those shown. For example, platforms 310 and/or 340 may include additional or alternative sensors (e.g., microphone 256, etc.), computing subsystems (e.g., navigation system 248, etc.), communication interfaces (e.g., wireless communication system 252, etc.), and/or any other component such as any of the components of vehicles 100 and 200. Thus, in some examples, device 300 can facilitate one way or two way communication between any number of devices (respectively distributed or coupled to platforms 310 and 340) via an optical communication path defined by light signals 360, 380, while also transmitting power from a stator platform (e.g., platform 340) to a rotor platform (e.g., platform 310) to power the various components coupled to the rotor platform.

FIG. 4A illustrates a side view of a device 400 that includes a rotary joint, according to an example embodiment. For example, device 400 may be similar to device 300, and can be used with an electromechanical system such as vehicles 100 and 200. As shown, device 400 includes platforms 410 and 440 that may be similar, respectively, to platforms 310 and 340. Further, as shown, device 400 also includes a plurality of light sources 412, 414, 416, 418 that may be similar to light source(s) 316. Further, as shown, device 400 includes light detector 452 that may be similar to detector(s) 352. Further, as shown, device 400 includes a magnetic core 490 extending through platforms 410 and 440. Core 490 can be similar to core 390, for example. In the example shown, a side 410a of platform 410 is positioned at a predetermined distance 404 to a side 440a of platform 440. In some examples, side 410a may correspond to a planar mounting surface of platform 410 (e.g., for mounting light sources 412, 414, 416, 418, etc., in a coplanar arrangement). Similarly, for example, side 440a may correspond to a planar mounting surface of platform 440 (e.g., for mounting detector 452 opposite to the light sources of platform 410). It is noted that some components of device 400 are omitted from

the illustration of FIG. 4A for convenience in description. For example, FIGS. 4B and 4C illustrate cross-section views of device 400.

In the cross section view shown in FIG. 4B, side 410a of platform 410 is pointing out of the page. As shown in FIG. 4B, device 400 also includes detector 432 that may be similar to detector 332, for example. Further, as shown, device 400 also includes light sources 420, 422, 424, 426, 428 that are arranged (along with light sources 412-418) in a substantially circular arrangement around axis of rotation 402 of platform 410. Further, as shown, device 400 also includes coil 430 disposed along planar mounting surface 410a around axis of rotation 402 of platform 410. For example, coil 430 may be similar to coil 330. Further, as shown, core 490 may have a cylindrical surface that remains within a predetermined distance 406 to coil 430 in response to rotation of platform 410 about axis of rotation 402. For example, core 490 could have an axis of cylinder aligned with axis of rotation 402 to facilitate coil 430 remaining within the distance 406 to core 490 as platform 410 rotates about axis 402.

In the cross section view shown in FIG. 4C, side 440a of platform 440 is pointing out of the page. As shown, platform 440 may also include a plurality of light sources, exemplified by light sources 444 and 446, which are also arranged in a circular arrangement around axis of rotation 402. Thus, in some examples, similarly to device 300, device 400 can be configured for two-way communication between platforms 410 and 440. For instance, light sources 412-428 of platform 410 can be configured to emit light propagating toward detector 452 of platform 440. Similarly, for instance, light sources of platform 440 (e.g., light sources 444, 446, etc.) can be configured to emit light propagating toward detector 432 of platform 410.

Further, as shown, device 400 also includes coil 450 disposed along planar mounting surface 440a around axis of rotation 402 of platform 410. For example, coil 450 may be similar to coil 350, and can be arranged to remain at least partially overlapping coil 430 in response to rotation of platform 410 about axis 402. In some examples, similarly to device 300, device 400 can be configured to cause an electrical current to flow through coil 450. As a result, coil 450 may generate a magnetic field that induces a corresponding electrical current to flow through coil 430. The induced electrical current can then be conditioned to provide power to various components (e.g., light sources 412-418) mounted to or otherwise coupled to platform 410. Further, similarly to coil 430, coil 450 may be configured to remain within distance 406 to core 490 in response to rotation of platform 410 about axis 402. For instance, coils 430 and 450 can be coaxially arranged about axis 402 (e.g., axis of cylinder of core 490) such that both coils remain within distance 406 to core 490 in response to rotation of platform 410 about axis 402.

Referring back to FIG. 4A, light sources 412, 414, 416, 418 may respectively emit a plurality of light beams 462 (extending between arrows 462a and 462b), 464 (extending between arrows 464a and 464b), 466 (extending between arrows 466a and 466b), and 468 (extending between arrows 468a and 468b). Further, as shown, adjacent light beams may intersect at or prior to arrival of the respective light beams at side 440a (and/or detector 452) of platform 440 to form a combined (e.g., continuous, etc.) light beam. As shown in FIG. 4B, for instance, light sources 420, 422, 424, 426, 428 can also emit light beams that intersect with respective adjacent light beams, similarly to light beams 462-468 emitted by light sources 412-418. As shown in FIG.

4C, for instance, light beams 470, 472, 474, 476, 478 that arrive at platform 440 may correspond, respectively, to light beams emitted by light sources 420, 422, 424, 426, 428. Together, for instance, light beams 462-478 may combine prior to propagation for predetermined distance 404 from platform 410 to form a continuous ring-shaped light beam extending around axis of rotation 402 as shown in FIG. 4C.

Thus, in line with the discussion above, detector 452 may continue to receive the combined light beam as platforms 410 and/or 440 rotate with respect to one another (e.g., about axis of rotation 402). By way of example, platform 410 and/or 440 can be rotated such that first side 410a and second side 440a remain within predetermined distance 404 to one another. For instance, platform 410 could be rotated about the shared (e.g., center) axis 402, while substantially remaining at least at predetermined distance 404 to platform 440. To that end, distance 404 could be any distance suitable for communication between one or more of light sources 412-428 and detector 452. For instance, as shown in FIG. 4A, distance 404 can be selected to be greater than a given distance at which adjacent light beams of light beams 462, 464, 466, 468 intersect. Alternatively, in another implementation (not shown), distance 404 can be selected to be equal to the given distance at which the adjacent light beams intersect. With either arrangement, the intersecting light beams can form a continuous or combined light beam incident on side 440a such that detector 450 (and/or 452) can remain overlapping the incident combined light beam as platform 410 rotates about axis 402.

The given distance at which adjacent light beams intersect, for instance, may depend on respective beam divergences of the adjacent light beams. The beam divergence of light beam 462, for instance, may correspond to the angle between arrows 462a and 462b and may be based on physical characteristics of a configuration of light source 412. For example, if the beam divergence of light beam 462 increases, then the distance (from side 410a) at which arrow 462b intersects with arrow 464a may decrease, and vice versa. Additionally or alternatively, for instance, the distance at which the adjacent light beams intersect may depend on a separation distance between adjacent light sources. For instance, if the separation distance between light sources 412 and 414 increases, then the distance (from side 410a) at which arrows 462b and 464a intersect may also increase. Accordingly, predetermined distance 404 can be based on an arrangement (e.g., separation distances) and/or beam divergence characteristics of light sources 412-428. Thus, in some examples, distance 404 can be adjusted by using fewer, more, or different light sources (e.g., having different beam divergences) than those shown, in accordance with various applications (e.g., size requirements, etc.) of device 400.

Additionally or alternatively, in some examples, detector 452 could be configured to remain overlapping the combined light beam in response to a different type of relative motion (e.g., other than a rotation) between platforms 410 and 440 even if the motion causes a change to distance 404. By way of example, an actuator (not shown) of device 400 could be configured to adjust the position of platform 410 along a translational path (e.g., along axis 402, along another linear axis, etc.), or other path (e.g., elliptical path, curved path, etc.). For instance, device 400 may be included in a computer numeric control (CNC) machine or a 3D printer that operates a tool (e.g., drill, saw, printer head, etc.) via a robotic arm or other hardware component. In this instance, platform 410 may be coupled to the tool, and platform 440 may be coupled to a controller (and/or an actuator) that

adjusts the position of platform 410 linearly along axis 402. In this instance, device 400 may be configured to restrict linear motion of platform 410 along axis 402 such that distance 404 remains sufficiently large for beams 462-468 to intersect prior to arrival of beams 462-468 at second side 440a (and/or detector 452). By doing so, for example, detector 452 may continue to receive the combined light beam as platforms 410 and/or 440 are linearly (or otherwise) displaced with respect to one another.

As noted above, in some scenarios, distance 404 may be selected to remain sufficiently large such that light beams 462-478 intersect to form a ring-shaped light beam incident on platform 440 (e.g., so that detector 452 remains overlapping the ring-shaped light beam as platform 410 rotates about axis 402). However, in some instances, the density of a magnetic field generated by coil 450 and extending through coil 430 may be directly proportional to distance 404 between the two platforms 410 and 440. As a result, the efficiency of power transmission from platform 440 to 410 can be affected by distance 404.

To mitigate the effect of distance 404, as shown, core 490 can be arranged to remain within a smaller distance 406 to both coils 430 and 450 in response to a relative motion (e.g., rotation, linear displacement, other motion, etc.) between platforms 410 and 440. Thus, in some instances, distance 406 may remain substantially unchanged even in scenarios where distance 404 changes. Further, similarly to core 390, core 490 can guide the magnetic field generated by coil 450 to extend through coil 430 (and within a small distance 406 to coil 430) regardless of distance 404 between the two platforms 410 and 440. With this arrangement, device 400 can provide efficient power transmission from platform 440 to platform 410 regardless of distance 404 between the two platforms. In one embodiment, distance 404 is approximately 1520 millimeters, distance 406 is approximately 0.5 millimeters, and transformer coils 430 and 450 facilitate transmission of at least 24 Watts of power. However, other distances and transmission powers are possible as well depending on various applications of device 400.

It is noted that the shapes, dimensions, and relative positions shown in FIGS. 4A-4C for device 400 and/or the various components thereof are not necessarily to scale and are only illustrated as shown for convenience in description. Thus, in some implementations, device 400 and/or one or more components thereof can have other forms, shapes, arrangements, and/or dimensions as well.

It is also noted that device 400 may include fewer or more components than those shown, such as any of the components of device 300 (e.g., actuators, sensors, controllers, etc.), among other possibilities. In one example, although device 400 is shown to include nine light sources mounted on each platform, device 400 can alternatively include more or fewer light sources. In another example, light sources 412-418 can be replaced with a single ring-shaped light source extending around axis 402 to provide a continuous (ring-shaped) light beam around axis 402. In yet another example, one or more light sources can be optically coupled to a light diffuser that redirects and/or focuses light from the light source(s) to form a ring-shaped light beam incident on platform 440. In still another example, although coil 430 (and 450) are respectively shown to include a single conductive loop, coil 430 and/or 450 can alternatively be implemented to include one or more additional conductive loops that are coplanar (e.g., conductive tracks along a single layer of a circuit board) and/or on a different geometric plane (e.g., conductive tracks along multiple layers of a circuit board).

FIG. 5 illustrates a cross-section view of another device 500 that includes a rotary joint, according to an example embodiment. Device 500 may be similar to device 400. For example, the cross-section view of device 500 shown may be similar to the view of device 400 shown in FIG. 4B. To that end, as shown, device 500 may include a planar mounting surface 510a (e.g., the side pointing out of the page) of a platform 510 that is similar to side 410a of platform 410. Further, for example, platform 510 may be configured to rotate about an axis of rotation 502 relative to another platform (not shown), similarly to rotation of platform 410 about axis 402. Further, as shown, device 500 includes a magnetic core 590 that may be similar to core 490 of device 400.

However, unlike device 400, device 500 includes a plurality of conductive loops 532, 534, 536 in a coplanar arrangement substantially parallel to side 510a of platform 510. By way of example, conductive loops 532, 534, 536 can be formed as conductive tracks patterned along a layer of a circuit board (e.g., PCB), similarly to coils 330, 350, 430, and 450. Together, conductive loops 532, 534, 536 form a multi-loop coil in which the plurality of conductive loops are concentric around axis of rotation 502 of platform 510. As shown, for instance, conductive loop 534 includes a substantially circular-arc shaped segment of conductive material extending between ends 534a and 534b, and having a center axis that is aligned along axis of rotation 502. Further, as shown, the multi-loop coil includes a segment of conductive material that extends from end 534b of loop 534 to end 532a of loop 532.

As shown, the plurality of conductive loops 532, 534, 536 are arranged in a coplanar arrangement along a first geometric plane (e.g., a surface of side 510a, etc.). In some examples, the multi-loop coil may also include one or more additional conductive loops (not shown) that are arranged in a coplanar arrangement along a second geometric plane that is substantially parallel to the first geometric plane. For example, the one or more additional conductive loops can be arranged similarly to loops 532, 534, 536 along a side of platform 510 that is opposite to side 510a (e.g., an opposite side of a circuit board).

Alternatively, the one or more additional conductive loops can be arranged along a layer inside platform 510. For instance, platform 510 may comprise a multi-layer PCB, and the additional loops can be patterned as tracks along any one of the PCB layers. To facilitate this, device 500 may include an electrical contact 540 that couples conductive loop 536 to a corresponding loop (not shown) along the second geometric plane (not shown). Electrical contact 540, for example, may include a conductive material that extends through the page toward an adjacent overlapping conductive loop (not shown) that is similar to loop 536. For instance, electrical contact 540 can be implemented as a "via" in a PCB, or conductive material that is deposited through a drilled hole between two layers of the PCB.

In some implementations, a multi-loop coil can be used with device 400 instead of a single-loop coil (e.g., coil 430) to provide an induced electrical current based on a magnetic field extending through core 490 for power reception. Alternatively or additionally, in some implementations, a multi-loop coil can be used instead of a single-loop coil (e.g., coil 450) to generate a magnetic field through magnetic core 490 for power transmission. A multi-loop coil may be able to support transmission or reception of a greater amount of power than a single-loop coil. Accordingly, in some implementations, one or both of coils 430 and 450 may be a multi-loop coil that includes a plurality of conductive loops.

It is noted that device 500 may include additional components such as controllers, light sources, detectors, etc., and/or any other component included in devices 300 and 400.

It should be understood that arrangements described herein are for purposes of example only. As such, those skilled in the art will appreciate that other arrangements and other elements (e.g. machines, interfaces, functions, orders, and groupings of functions, etc.) can be used instead, and some elements may be omitted altogether according to the desired results. Further, many of the elements that are described are functional entities that may be implemented as discrete or distributed components or in conjunction with other components, in any suitable combination and location, or other structural elements described as independent structures may be combined.

While various aspects and embodiments have been disclosed herein, other aspects and embodiments will be apparent to those skilled in the art. The various aspects and embodiments disclosed herein are for purposes of illustration and are not intended to be limiting, with the true scope being indicated by the following claims, along with the full scope of equivalents to which such claims are entitled. It is also to be understood that the terminology used herein is for the purpose of describing particular embodiments only, and is not intended to be limiting.

What is claimed is:

1. A device comprising:
 - a rotor platform that rotates about an axis of rotation, the rotor platform including a rotor planar mounting surface;
 - a rotor coil comprising a first plurality of conductive loops disposed along the rotor planar mounting surface;
 - a stator platform including a stator planar mounting surface;
 - a stator coil comprising a second plurality of conductive loops disposed along the stator planar mounting surface, wherein the rotor coil and the stator coil are coaxially arranged about the axis of rotation, and wherein the stator coil remains within a first predetermined distance to the rotor coil in response to rotation of the rotor platform about the axis of rotation; and
 - a magnetic core extending along the axis of rotation and through the stator coil, wherein the magnetic core remains within a second predetermined distance to the stator coil in response to rotation of the rotor platform about the axis of rotation.
2. The device of claim 1, wherein the magnetic core also extends through the rotor coil, and wherein the magnetic core remains within the second predetermined distance to the rotor coil in response to rotation of the rotor platform about the axis of rotation.
3. The device of claim 1, further comprising:
 - a plurality of light sources mounted on the rotor planar mounting surface in a circular arrangement about the axis of rotation, wherein the plurality of light sources emit a plurality of diverging light beams toward the stator planar mounting surface, wherein adjacent light beams of the plurality intersect at a given distance to the rotor planar mounting surface to form a ring-shaped light beam incident on the stator planar mounting surface, and wherein the given distance is less than or equal to the first predetermined distance; and
 - a light detector mounted on the stator planar mounting surface, wherein the light detector remains at least

partially overlapping the ring-shaped light beam in response to rotation of the rotor platform about the axis of rotation.

4. The device of claim 1, wherein the first predetermined distance is greater than the second predetermined distance.
5. The device of claim 1, wherein the rotor planar mounting surface remains substantially parallel to the stator planar mounting surface in response to rotation of the rotor platform about the axis of rotation.
6. The device of claim 1, further comprising:
 - a sensor mounted on the rotor platform; and
 - circuitry coupled to the rotor coil, wherein the circuitry conditions an induced electrical current flowing through the rotor coil, wherein the induced electrical current is based on a corresponding electrical current flowing through the stator coil, and wherein the circuitry provides the conditioned electrical current to power the sensor.
7. A device comprising:
 - a first platform having a first side;
 - a second platform having a second side positioned to overlap the first side of the first platform;
 - an actuator that rotates the first platform relative to the second platform and about an axis of rotation of the first platform, wherein the first side remains within a first predetermined distance to the second side in response to the actuator rotating the first platform;
 - a first coil included in the first platform, the first coil comprising a first plurality of conductive loops in a coplanar arrangement substantially parallel to the first side;
 - a second coil included in the second platform, the second coil comprising a second plurality of conductive loops in a coplanar arrangement substantially parallel to the second side; and
 - a magnetic core extending through the first coil and the second coil, wherein a surface of the magnetic core adjacent to the first coil remains within a second predetermined distance to the first coil in response to the actuator rotating the first platform.
8. The device of claim 7, wherein the surface of the magnetic core has a substantially cylindrical shape defined by an axis of cylinder aligned with the axis of rotation of the first platform.
9. The device of claim 7, wherein the surface of the magnetic core also remains within the second predetermined distance to the second coil in response to the actuator rotating the first platform.
10. The device of claim 7, wherein the first predetermined distance is greater than the second predetermined distance.
11. The device of claim 7, wherein the first plurality of conductive loops of the first coil are concentrically arranged about the axis of rotation of the first platform, and wherein the second plurality of conductive loops of the second coil are concentrically arranged about the axis of rotation of the first platform.
12. The device of claim 7, wherein the first plurality of conductive loops of the first coil is coplanar along a first geometric plane, and wherein the first coil further comprises a third plurality of conductive loops in a coplanar arrangement along a second geometric plane that is substantially parallel to the first geometric plane.
13. The device of claim 12, further comprising:
 - an electrical contact that electrically couples the first plurality of conductive loops to the third plurality of conductive loops, the electrical contact extending between a given conductive loop of the first plurality of

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conductive loops and an adjacent conductive loop of the third plurality of conductive loops, wherein the given conductive loop overlaps the adjacent conductive loop.

14. The device of claim 7, wherein the first platform comprises a printed circuit board (PCB), wherein the first plurality of conductive loops comprise conductive tracks patterned along a single layer of the PCB, and wherein the first plurality of conductive loops comprise:

- a first conductive loop having a first substantially circular-arc shaped segment of conductive material, wherein a center axis of the circular-arc shaped segment is aligned along the axis of rotation of the first platform;
- a second conductive loop having a second substantially circular-arc shaped segment of conductive material concentrically arranged with the first conductive loop about the center axis; and
- a segment of conductive material extending from an end of the first substantially circular-arc shaped segment to an end of the second substantially circular-arc shaped segment.

15. The device of claim 7, further comprising:

- a plurality of light sources included in the first platform and mounted in a circular arrangement about the axis of rotation, wherein the plurality of light sources emit light toward the second side of the second platform; and
- a light detector included in the second platform to receive light emitted by at least one of the plurality of light sources.

16. The device of claim 15, wherein the plurality of light sources emit a plurality of diverging light beams toward the second side of the second platform,

wherein the plurality of light beams intersect at least at the first predetermined distance from the first platform to form a ring-shaped light beam incident on the second side of the first platform, and

wherein the light detector remains at least partially overlapping the ring-shaped light beam in response to the actuator rotating the first platform about the axis of rotation.

17. A device comprising:

- a rotor platform that rotates about an axis of rotation;
- a rotor printed circuit board (PCB) mounted to the rotor platform;
- a stator platform;
- a stator PCB mounted to the stator platform, wherein the rotor PCB remains at a first predetermined distance to

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the stator PCB in response to rotation of the rotor platform about the axis of rotation;

a rotor coil comprising one or more conductive loops patterned along a single layer of the rotor PCB;

a stator coil comprising one or more conductive loops patterned along a single layer of the stator PCB, wherein the rotor coil and the stator coil are concentrically arranged about the axis of rotation such that the rotor coil remains at least partially overlapping the stator coil responsive to rotation of the rotor platform about the axis of rotation; and

a magnetic core extending through the rotor coil and the stator coil, wherein a surface of the magnetic core remains at a second predetermined distance to the rotor coil and the stator coil responsive to rotation of the rotor coil about the axis of rotation.

18. The device of claim 17, further comprising:

- one or more additional conductive loops patterned along another single layer of the rotor PCB, wherein the one or more additional conductive loops are concentrically arranged about the axis of rotation of the rotor platform, and wherein the one or more conductive loops of the single layer overlap the one or more additional conductive loops of the other single layer; and
- an electrical contact electrically coupling the one or more conductive loops in the single layer of the rotor PCB to the one or more additional conductive loops of the other single layer.

19. The device of claim 17, further comprising:

a plurality of light sources mounted to the rotor PCB in a circular arrangement about the axis of rotation, wherein the plurality of light sources emit a plurality of diverging light beams to form a ring-shaped light beam incident on the stator PCB, wherein a given light beam of the plurality intersects with an adjacent light beam of the plurality at a given distance to the rotor platform, and wherein the given distance is less than the first predetermined distance; and

a light detector mounted to the stator PCB, wherein the light detector remains at least partially overlapping the ring-shaped light beam in response to rotation of the rotor platform about the axis of rotation.

20. The device of claim 17, wherein the first predetermined distance is greater than the second predetermined distance.

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