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(54) **RIDE-ON LAWNMOWER**

AUFSITZRASENMÄHER

TONDEUSE À GAZON AUTOPORTÉE

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Description**TECHNICAL FIELD**

[0001] This invention relates to a riding lawn mower. Specifically, the present invention relates to a riding lawn mower of a generic type as defined in the generic part of the independent claim attached.

BACKGROUND

[0002] Document US 2012/0136539 A1 discloses a riding lawn mower of the generic type defined above.

[0003] A riding lawn mower configured with only one operation mode, such as, only one starting mode, cannot meet a user's need when the user needs to start up quickly, because of the fixed starting acceleration.

[0004] A further mower is e.g. known from US 2003/080704 A1.

SUMMARY

[0005] The invention provides a riding lawn mower with multiple operation modes. Specifically, the invention provides a riding lawn mower as defined in the independent claim attached.

[0006] Preferred embodiments of the inventions are defined in the dependent claims attached.

BRIEF DESCRIPTION OF THE DRAWINGS**[0007]**

FIG. 1 is an external view of a riding lawn mower from a perspective;

FIG. 2 is an external view of the riding lawn mower from another perspective;

FIG. 3a is a communication system of the riding lawn mower according to an embodiment;

FIG. 3b is a communication system of the riding lawn mower according to another embodiment;

FIG. 4 is a schematic diagram of a connection of negative terminals of various modules of the riding lawn mower according to an embodiment;

FIG. 5 is a structural diagram of an electric control system of an embodiment of the riding lawn mower from a perspective;

FIG. 6 is a structural diagram of the electric control system of the embodiment of the riding lawn mower from another perspective;

FIG. 7 is a first heat sink of the riding lawn mower;

FIG. 8 is a structural diagram of the riding lawn mower from another perspective;

FIG. 9a is a structural diagram of a circuit board including a cover from a perspective;

FIG. 9b is a structural diagram of the circuit board including the cover from another perspective;

FIG. 10 is a structural diagram of the circuit board and the cover separated from each other from a perspective;

FIG. 11 is a structural diagram of the circuit board and the cover separated from each other from another perspective;

FIG. 12 is a structural diagram of the riding lawn mower from another perspective;

FIG. 13 is an operation panel of the riding lawn mower;

FIG. 14 is a control system of a walking motor of the riding lawn mower;

FIG. 15 is a specific control circuit of the walking motor of the riding lawn mower;

FIG. 16 is a walking control module of the riding lawn mower according to an embodiment;

FIG. 17 is a flowchart of a control method of the riding lawn mower according to an embodiment;

FIG. 18 is a flowchart of a control method of the riding lawn mower according to another embodiment; and

FIG. 19 is a flowchart of a control method of the riding lawn mower according to another embodiment.

DETAILED DESCRIPTION

[0008] Those skilled in the art should understand that, in the disclosure of this invention, the terms "up", "down", "front", "rear", "left", "right" and the like indicate the orientation or positional relationship based on the orientation or positional relationship shown in the drawings, which are only for the convenience of describing the present invention, and do not indicate or imply that the device or element referred to must have a specific orientation, or be constructed and operated in a specific orientation, and therefore the above terms should not be understood as a limitation of the present invention.

[0009] Referring to FIG. 1, a riding lawn mower 100 includes: a power output assembly 11, a walking assembly 12, an operating component 13, a power supply assembly 14, a seat 15, a chassis 16, and a lighting as-

sembly 17.

[0010] The chassis 16 is configured to carry the seat 15, and the chassis 16 at least partially extends in a front and rear direction; the seat 15 is for an operator to sit on, and the seat 15 is mounted on the chassis 16.

[0011] For the convenience of description, the direction in which the operator sits on the seat is defined as the front or the front side of the riding lawn mower, and the direction opposite to the front is defined as the rear or rear side of the riding lawn mower, and the operator's left hand direction is defined as the left or left side of the riding lawn mower 100, and the operator's right hand direction is defined as the right or right side of the riding lawn mower 100.

[0012] The power output assembly 11 includes an output member for outputting power to achieve certain mechanical function. For example, in this embodiment, the output member may be a mowing element 111 for achieving a mowing function, and the power output assembly 11 is also connected to the chassis 16. The power output assembly 11 also includes a cutting motor 112 for driving the mowing element 111 to rotate at a high speed and a cutting control module 113 for controlling the cutting motor 112. The power output assembly 11 may include more than one mowing elements 111, and correspondingly, the number of cutting motors 112 may correspond to the number of mowing elements 111. The cutting motors 112 are controlled by the cutting control module 113. In some specific embodiments, the cutting control module 113 includes a control chip, such as MCU, ARM, and so on.

[0013] In order to obtain a better mowing effect, optionally, the power output assembly 11 may include two mowing elements 111, and correspondingly, two cutting motors 112, namely a left cutting motor 112L and a right cutting motor 112R. Optionally, the two cutting motors 112 are respectively controlled by two cutting control modules 113, and the two cutting control modules 113 are a left cutting control module 113L and a right cutting control module 113R, respectively. That is, the power output assembly 11 includes two cutting control modules 113, and cutting two motors 112. Alternatively, the power output assembly 11 may include only one cutting control module 113, which controls two cutting motors 112 at the same time.

[0014] The walking assembly 12 is configured to enable the riding lawn mower 100 to walk on the lawn. The walking assembly 12 may include first walking wheels 121 and second walking wheels 122, the number of the first walking wheels 121 is two, and the number of the second walking wheels 122 is also two, including a left drive wheel 122L and a right drive wheel 122R. The walking assembly 12 may also include walking motors 123 for driving the second walking wheels 122, and the number of walking motors 123 is also two, namely a left walking motor 123L and a right walking motor 123R, respectively. In this way, when the two walking motors 123 drive the corresponding second walking wheels 122 to rotate at different speeds, a speed difference is generat-

ed between the two second walking wheels 122, so as to steer the riding lawn mower 100. The walking assembly 12 includes two walking control modules 124, the two walking control modules 124 are a left walking control module 124L and a right walking control module 124R, respectively, which are used to control the left walking motor 123L and the right walking motor 123R, respectively. In some specific embodiments, the walking control module 124 includes a control chip, such as MCU, ARM, and so on.

[0015] The power supply assembly 14 is configured to provide electric power for the riding lawn mower 100. Optionally, the power supply assembly 14 is configured to at least supply power to the cutting motors 112 and the walking motors 123, and the power supply assembly 14 may also supply power to other electronic components in the riding lawn mower 100, such as the cutting control module 113 and the walking control module 124.

[0016] In some embodiments, the power supply assembly 14 is provided on the rear side of the seat 15 on the chassis 16. In some embodiments, the power supply assembly 14 includes a plurality of battery packs 141 capable of supplying power to the power tool 200. The battery packs 141 are configured to be pluggably mounted to the riding lawn mower 100 by the user. The installation and removal of the battery packs 141 by plugging and unplugging makes the operation more convenient and also the placement of the battery packs 141 more accurate. Optionally, the battery pack 141 includes a plurality of battery cells connected in series, in parallel, or in a combination of series and parallel. A plurality of battery cells are coupled in a battery casing to form a whole, and the battery cell may be a lithium battery cell. The power tool 100 may be a gardening tool such as a string trimmer, a hedge trimmer, a blower, a chain saw, etc., and may also be a torque output tool such as an electric drill, an electric hammer, etc., and may also be a sawing tool such as an electric circular saws, a jig saw, and a reciprocating saw, etc., and may also be a grinding tool such as an angle grinder, a sanding machine, etc. In some other embodiments, the battery pack 141 may also be configured to power a hand-push power tool, such as a hand-push lawn mower, a hand-push snow blower, and so on. In this way, the battery pack 141 applied to the riding lawn mower of the present invention can be unplugged by the user to be applied to the above power tools. In other words, the user can also borrow the battery pack 141 in these power tools to power the riding lawn mower 100, thereby improving the versatility of the riding lawn mower 100 and reducing the usage cost. The power supply assembly 14 includes a battery compartment 144 for placing the battery packs 141. The number of battery compartment 144 may be one, which stores multiple battery packs 144, or may be multiple, for example, the same as the number of battery packs 141, wherein each battery compartment 144 stores one battery pack 141.

[0017] The power supply assembly 14 further includes a power supply management module 142 for controlling

the operation of the power supply assembly 14. In this embodiment, the power supply management module 142 is configured to control the safe discharge of the plurality of battery packs 141, so that the riding lawn mower 100 can operate normally. In some specific embodiments, the power supply management module 142 includes a control chip, such as MCU, ARM, and so on.

[0018] The riding lawn mower 100 further includes a walking control module 124 for controlling the walking process of the riding lawn mower 100. The walking control module 124 is at least used to control the walking motors 123 of the walking assembly 12 to control the walking process of the riding lawn mower 100. The walking control module 124 can control the walking motors 123 to start.

[0019] The operating component 13 is operable by the user, and the user sends control instructions through the operating component 113 to control the operation of the riding lawn mower 100. The operating component 13 can be operated by the user to set the target speed, travel direction, etc. of the riding lawn mower 100. In other words, the operating component 13 can be operated by the user to set the target operating state of the riding lawn mower 100. The operating component 13 includes an operating mechanism 131 and an operation sensing module 132 enabled to sense changes in the state of the operating mechanism.

[0020] In some specific embodiments, the operating mechanism 131 includes at least one operating lever, and the operation sensing module 132 includes at least one position sensor. The operating lever may be arranged on either sides or a periphery of the seat 15. Different positions of the operating lever correspond to different target states of the riding lawn mower. By pushing the operating lever to the target positions, the user controls the riding lawn mower 100 to reach the target states corresponding to the target positions reached by the operating lever, including the traveling direction, traveling speed, parking, braking, deceleration, etc. In a specific embodiment, the operating levers include a left operating lever 131L and a right operating lever 131R, and the walking motors 123 include the left walking motor 123L and the right walking motor 123R. The left operating lever and the right operating lever are used to respectively control the left walking motor 123L and the right walking motor 123R, so as to respectively control the two second walking wheels 122. The position sensor is configured to detect the position of the operating lever. When the operating lever is in different positions, the position sensor outputs detected signals representing different positions.

[0021] The operating mechanism 131 may further include at least one switch triggerable to change its state so as to set the riding lawn mower 100 in different target states. The operation sensing module 132 includes a switch state detection assembly, and the switch state detection assembly is configured to detect the state of at least one switch. For example, a seat switch arranged

under the seat 15 can sense the user sitting on the seat or leaving the seat; a start switch can start the riding lawn mower 100 when the user presses this switch; a key switch start the walking motor 123 when the user inserts the key and rotates to the on position or the off position. The switch state detection assembly can detect the different states of each switch and send the detected information to the required module.

[0022] The operating mechanism of the operating component 13 may also include a combination of one or more operating mechanisms such as a pedal, a switch, a handle, and a steering wheel, for example, the manual operating lever, combined with a foot brake pedal, a speed pedal and a steering wheel is configured for the user to operate the riding lawn mower 100. The operating component 13 may also be a control panel, which includes a plurality of buttons, and different buttons correspond to different control commands. The user inputs different control commands through the switch to control the walking motor 123 of the walking assembly 12. Refer to the communication system of the riding lawn mower 100 according to an embodiment shown in FIG. 3a, the riding lawn mower 100 further includes a bus module 18, and the bus module 18 is connected with a variety of modules, for example, the bus module 18 is at least connected with the cutting control module 113, the walking control module 124, the operation sensing module 132, the power supply management module 142 in order to transmit data between the cutting control module 113, the walking control module 124, the operation sensing module 132, and the power supply management module 142. The cutting control module 113, the walking control module 124, the operation sensing module 132, and the power supply management module 142 can all send data to the bus module 18, and receive data through the bus module 18. When sending data, these modules cannot send data at the same time. At most one device can send data at any time. Each device may obtain the bus control right to send data by competing for the busy line B/F, and the module that obtains the bus control right realize occupation and release of the bus through a "busy bus" signal and an "idle bus" signal. When receiving data, all modules can receive information from the bus module 18, and determine of the information is related to themselves, if yes, then perform corresponding processing, if not, continue the original work. Optionally, the riding lawn mower 100 further includes a lighting assembly for illuminating functions; a lighting control module 172 for controlling the operation of the illuminating light 171, and the lighting control module 172 is connected to the bus module 18. The lighting control module 172 controls the illuminating light 171 to turn on upon receiving a signal that requires lighting.

[0023] In an embodiment, the user expects the riding lawn mower 100 to go straight forward at a maximum speed. In a specific implementation, the user operates the operating mechanism 131 to a certain state and issues a command to go straight forward at the maximum

speed; the operation sensing module 132 detects command to go straight forward at the maximum speed, which corresponds to the current state of the operating lever of the operating mechanism 131, and sends detected information including the position of the operating lever to the bus module 18; the bus module 18 broadcasts the information to all modules connected to the bus module 18; the walking control module 124, the cutting control module 113, the operation sensing module 132 and the power supply management module 142 receive the information including the position of the operating lever through the bus, and determine the data is related to themselves. At this time, the cutting control module 113 controls the cutting motor to stop working; and according to the acquired signal of the operation sensing module 132, the two walking control modules 124 obtain the rotational speed and the rotational direction of the two walking motors 123 corresponding to the signal through calculation or lookup table. Both walking motors 123 run at the maximum forward rotational speed, so that the riding lawn mower 100 moves straight forward in accordance with the target state set by the operating mechanism.

[0024] Similarly, the user controls the riding lawn mower 100 by operating the operating mechanism 131, including controlling the mowing speed, traveling direction and speed of the riding lawn mower 100.

[0025] Referring to a communication system of the riding lawn mower 100 according to another embodiment as shown in FIG. 3b, which is different from the communication system of the riding lawn mower shown in FIG. 3a in that: there are two cutting control modules 113, namely a left cutting control module 113L and a right cutting control module 113R, which are respectively configured to control a left cutting motor 112L and a right cutting motor 112R; there are two walking control modules 124, namely a left walking control module 124L and a right walking control module 124R, which are respectively configured to control a left walking motor 123L and a right walking motor 123R; there are two operating mechanisms 131 and two operation sensing modules 132: a left operating mechanism 131L configured to control a left walking motor 123L, and a right operating mechanism 131R configured to control a right walking motor 123R, a left operation sensing module 132L configured to sense the state of the left operating mechanism 131L, and a right operation sensing module 132R configured to sense the state of the right operating mechanism 131R.

[0026] In an embodiment, when braking is needed, if the left walking motor 123L has a braking abnormality, the left walking control module 124L sends a signal to the bus module 18, and other modules can receive information on the braking abnormality of the left walking motor 123L from the bus module 18. After receiving the braking abnormality signal, the right walking control module 124R still controls the right walking motor 123R to brake normally. Optionally, when any one of the walking motors has a braking abnormality, the parking mode is automatically triggered, and the riding lawn mower 100 enters

the parking mode. This can ensure that the riding lawn mower 100 is parked and stopped when there is a braking abnormality, thereby reducing the occurrence of safety accidents.

[0027] Referring to FIG. 4, in an embodiment, the chassis 16 is made of a metallic material, the negative terminals of at least the cutting control module 113, the walking control module 124, and the power supply management module 142 are connected with the chassis 16. The negative terminals of other modules may also be connected to the chassis, including the lighting control module 172 and the operation sensing module 132. In this way, the chassis 16 could be used as the negative terminal of the electric control system of the riding lawn mower 100, which reduces the wiring and cost, and facilitates assembly.

[0028] Referring to FIG. 5, according to an embodiment of the riding lawn mower 100, the electric control system includes the left cutting control module 113L, the right cutting control module 113R, the left walking control module 124L, the right walking control module 124R, the bus module 18, the power supply management module 142, the left operation sensing module, the right operation sensing module, and a power supply positive junction box 25. Optionally, the lighting control module 172 is also included.

[0029] The left cutting control module 113L is configured to control the left cutting motor 112L. The right cutting control module 113R is configured to control the right cutting motor 112R. The left walking control module 124L is configured to control the left walking motor 123L. The right walking control module 124R is configured to control the right walking motor 123R.

[0030] The power supply management module 142 is configured to coordinate and control the discharge process of at least one battery pack 141. The electric energy discharged by the at least one battery pack 141 is distributed to other modules through the power supply positive junction box 25, for example, the left cutting control module 113L, the right cutting control module 113R, the left walking control module 124L, the right walking control module 124R, the bus module 18 and so on.

[0031] The bus module 18 is in commutation connection with the left cutting control module 113L, the right cutting control module 113R, the left walking control module 124L, the right walking control module 124R, the power supply management module 142, the left operation sensing module (not shown), and the right operation sensing module (not shown), the power supply positive junction box 25 and the lighting control module 172.

[0032] The riding lawn mower 100 includes at least one circuit board 19 for installing the cutting control module 113, the walking control module 124, and the power supply management module 142, and optionally, the operation sensing module, the bus module 18 and the lighting module 171. The circuit board 19 is provided with electronic components, and the electronic components include a controller, a hardware circuit that cooperates with

the controller, and the like.

[0033] Optionally, the riding lawn mower 100 includes a plurality of circuit boards 19 for respectively installing the cutting control module 113, the walking control module 124, the operation sensing module 132, the power supply management module 142, and the bus module 18. Each of the circuit boards is arranged separately. The advantage is that the above-mentioned modules are separately arranged on different circuit boards, which is convenient for installation and disassembly, facilitates independent maintenance, and reduces maintenance costs.

[0034] As an optional solution, the left cutting control module 113L, right cutting control module 113R, left walking control module 124L, right walking control module 124R, bus module 18, power supply management module 24, left operation sensing module 132L, right operation sensing module 132R, and the lighting control module 27 include a circuit board, and each module is separately arranged on a plurality of different circuit boards, that is, each module is separately arranged on a circuit board. In this way, each module is self-contained, easy to install and maintain separately, and reduce maintenance costs.

[0035] Optionally, the left cutting control module 113L, the right cutting control module 113R, the left walking control module 124L, the right walking control module 124R, the bus module 18, the power supply management module 142, the left operation sensing module 132L, the right operation sensing module 132R, and the lighting control module 172 are all provided with an interface group. The interface group is provided with multiple interfaces.

[0036] Referring to FIGS. 5 and 6, a left cutting control module 113L is provided with a left cutting motor interface 114L and a communication interface 115L, which are respectively used for connecting the left cutting motor 112L and the bus modules 18. Similarly, the right cutting control module 113R is provided with a right cutting motor interface 114R and a communication interface 115R, which are respectively used for connecting the right cutting motor 112R and the bus module 18.

[0037] The left walking control module 124L is provided with a left walking motor interface 125L and a communication interface 126L, which are respectively used for connecting the left cutting motor 123L and the bus module 18. The right cutting control module 124R is provided with a right cutting motor interface 125R and a communication interface 126R, which are respectively used for connecting the right cutting motor 123R and the bus module 18. The lighting control module 172 is provided with an interface 173 for connecting the illuminating light 171.

[0038] The power supply management module 142 is provided with a plurality of battery pack interfaces 143 for connecting with the plurality of battery packs 141. The power supply management module 142 is also provided with a bus positive output terminal, which is connected to the power supply positive junction box 25, and a plurality of positive output terminals are branched out

through the power supply positive junction box 25. The plurality of positive output terminals are used to connect with the power ports of other modules to provide electric power to other modules. The power supply management module 142 is also provided with a communication interface for connecting the bus module 18 through a communication wire.

[0039] The bus module 18 is also provided with multiple interfaces, including a communication interface for connecting each module and a positive power terminal. For example, the bus module 18 is provided with a communication interface 133L for connecting the left operation sensing module 132L and a communication interface 133R for connecting the right operation sensing module 132R. The bus module 18 has a plurality of communication interfaces for connecting with the above-mentioned modules through communication wires. Optionally, the communication interface is a type-C interface to facilitate insertion and assembly.

[0040] In this way, each module can be connected to other external modules or components through an interface, so that the modules can be connected to each other through a wire and without complicated circuit design and layout, making the structure of the electric control system of the riding lawn mower 100 more compact, reliable, and simple, and making the modules easy to replace, repair and assemble.

[0041] When the interface group is provided with multiple interfaces, each interface can be connected to wires of different colors or lengths, which can effectively prevent the wires from being connected incorrectly and damaging the electrical components.

[0042] Optionally, the plurality of circuit boards and the plurality of modules are arranged under the seat 15. This has the advantage of saving space, lowering the center of gravity of the whole machine, and making the operation of the riding lawn mower safer and more stable. In this embodiment, the left cutting control module 113L, the right cutting control module 113R, the left walking control module 124L, the right walking control module 124R, the bus module 18, and the lighting control module 172 are arranged under the seat 15, and the left operation sensing module 132L is arranged near the left operating mechanism 131L, and the right operation sensing module 132R is arranged near the right operating lever 131R.

[0043] Optionally, the power supply management module 142 may be arranged on the lower rear side of the seat 15, at a position close to the front of the battery compartment 144, to save space.

[0044] Referring to FIGS. 9-11, optionally, a detachable cover 20 is provided on the circuit board 19, the cover 20 is at least partially located above the core components on the circuit board, for example, above the controller to protect the components on the circuit board. Optionally, the cover 20 is provided in a semi-open form. In other words, the cover is not completely closed, so that external airflow can flow through the electronic components on the circuit board, which improves the cooling effect of the

control module and the components.

[0045] Optionally, the riding lawn mower 100 further includes a metal plate 21, which is disposed on the lower side of at least one of the cutting control module 113, the walking control module 124, and the power supply management module 142. The negative terminal of at least one of the cutting control module 113, the walking control module 124, and the power management module 142 is connected to the metal plate.

[0046] In an optional embodiment, the cutting control module 113 includes a left cutting control module 113L and a right cutting control module 113R, and the walking control module 124 includes a left walking control module 124L and a right walking control module 124R. The left cutting control module 113L and the left walking control module 124L share a metal plate, the right cutting control module 113R and the right walking control module 124R share a metal plate, and the bus module 18 and the lighting control module 172 share a metal plate. The power supply management module 142 uses a metal plate alone. The above-mentioned left cutting control module 113L, right cutting control module 113R, left walking control module 124L, right walking control module 124R, bus module 18, and lighting control module 172 can all share a metal plate, that is, the negative terminals of the above modules are all connected to the same metal plate.

[0047] Optionally, the metal plate is made of aluminum material. The advantage is that the negative terminal of each module can be connected through the metal plate 21, thereby reducing the wiring, simplifying the wiring difficulty, reducing the cost, and facilitating maintenance.

[0048] Referring to FIGS. 5-8, the riding lawn mower 100 includes a heat sink for cooling the electrical control system. Optionally, the riding lawn mower 100 includes a first heat sink 31, which is located close to the cutting control module 113 and/or the walking control module 124 and faces the ground, which is mainly used to cool the controller in the control module and the electronic components that generate heat.

[0049] The first heat sink 31 includes a plurality of cooling fins, and the plurality of cooling fins are vertically arranged at the bottom of the circuit board of the cutting control module 113 and/or the walking control module 124 to increase the cooling area. The cooling fins are arranged in parallel with the front and rear direction of the riding lawn mower. When the riding lawn mower 100 is walking, the airflow flows through the cooling fins, creating a good cooling effect.

[0050] In an alternative embodiment, the cutting control module 113 includes a left cutting control module 113L and a right cutting control module 113R, the walking control module 124 includes a left walking control module 124L and a right walking control module 124R, and the first heat sink 31 includes a left cutting heat sink 311L, a right cutting heat sink 311R, a left walking heat sink 312L and a right heat heat sink 312R, wherein the left cutting heat sink 311L is disposed on the lower side of the left cutting control module 113L, and the right cutting heat

sink 311R is disposed on the lower side of the right cutting control module 113R, the left walking heat sink 312L is disposed on the lower side of the left walking control module 124L, and the right cutting heat sink 311R is disposed on the lower side of the right walking control module 124R.

[0051] Optionally, the first heat sink 31 further includes a lighting control heat sink 313, which is disposed on the lower side of the lighting control module 172 for cooling the lighting control module 172.

[0052] The first heat sink 31 is disposed facing the ground. In the embodiment with the metal plate 21, the first heat sink 31 is disposed on the lower side of the metal plate 21. When the riding lawn mower 100 is walking, the airflow flows through the first heat sink 31 to take away the heat of the first heat sink 31 and the above-mentioned control module, creating a good cooling effect. The number of first heat sinks 31 of the riding lawn mower 100 can be configured according to actual cooling requirements.

[0053] Optionally, the riding lawn mower 100 includes a second heat sink 32, and the second heat sink 32 is disposed close to the power supply management module 142 and facing the front of the riding lawn mower 100.

[0054] The second heat sink 32 includes a plurality of cooling fins, and the plurality of cooling fins are vertically arranged at the bottom of the circuit board of the power supply management module 142 facing the front of the riding lawn mower 100 to increase the cooling area. The cooling fins are arranged substantially in parallel with the up and down direction of the riding lawn mower. When the riding lawn mower 100 is walking, the airflow flows through the cooling fins, creating a good cooling effect.

[0055] The second heat sink 32 is used for cooling the power supply management module 142, and is mainly used for the controller in the power supply management module and the electronic components that are prone to generate heat. When the riding lawn mower 100 travels forward, the airflow from the front of the riding lawn mower 100 flows through the second heat sink 32, taking away the heat from the power supply management module 142 and the second heat sink 32, creating a good cooling effect.

[0056] Referring to FIG. 12, in an embodiment, the operating component 13 is operable by the user to allow the operator to control the riding lawn mower 100. The operating component 13 includes a first operating component 134; the first operating component 134 sets the starting mode of the walking motor 123; the first operating component 134 has a first operating state and a second operating state. The first operating state is configured to start the walking motor 123 in the first starting mode. In the first starting mode, the walking motor 123 starts at a first starting acceleration. The second operating state is configured to start the walking motor 123 in the second starting mode. In the second starting mode, the walking motor 123 starts at a second starting acceleration. The first starting acceleration is less than the second starting

acceleration.

[0057] As an alternative, the first operating component 134 is provided on the operation panel 22 (FIG. 13), and the first operating component 134 includes different starting mode buttons, such as a first starting mode button 1341 and a second starting mode button 1342. When the first starting mode button 1341 is pressed, the first operating component 134 is in the first operating state. When the first starting mode button 1341 is pressed, the first operating component 134 is in the first operating state. When the second starting mode button 1432 is pressed, the first operating component 134 is in the second operating state. The first operating component 134 may also be separately provided outside the operation panel 22. The operation panel 22 may be a touch display screen.

[0058] In some embodiments, the first operating component 134 also has a third operating state, and the third operating state is configured to trigger the walking motor 123 to start in a third starting mode. For example, the first operating component 134 may be the aforementioned operation panel 22, and the first operating component 134 further includes a third starting mode button 1343. When the third starting mode button 1343 is pressed, the first operating component 134 is in the third operating state. At this time, the walking motor 123 starts in the third starting mode. In the third starting mode, the walking motor 123 starts at a third starting acceleration, and the third starting acceleration is greater than the second starting acceleration.

[0059] Optionally, when the first operating component 134 is in the third operating state, the walking control module 124 controls the walking motor 123 to start in the third starting mode, the walking motor 123 starts at the third starting acceleration, and the third starting acceleration is greater than the second starting acceleration.

[0060] By configuring multiple starting accelerations, different starting modes can be provided. When the user needs to start quickly, the user can choose the third starting mode with a large starting acceleration to start at the third starting acceleration. When the user needs to start slowly, the user can choose the first starting mode with a small starting acceleration to start at the first starting acceleration. Different user experiences can be accommodated.

[0061] As an optional solution, when the power supplied by the power supply assembly 14 is a first power, the walking motor 123 starts at the first starting acceleration in the first starting mode, and the walking motor 123 starts at the second starting acceleration in the second starting mode. When the power supplied by the power supply assembly 14 is a second power, the walking motor 123 starts at the third starting acceleration in the first starting mode, and the walking motor 123 starts at the fourth starting acceleration in the second starting mode.

[0062] In some specific embodiments, the power supply assembly 14 includes a plurality of battery packs 141, the more the number of dischargeable battery packs 141 inserted into the riding lawn mower 100 or the sum of the

number of cell groups connected in parallel in all battery packs 141, the more power the power supply assembly 14 can provide to the walking motor 123. In order to make full use of the power when the power supplied by the power supply assembly 14 is high, to meet the needs of users for quick start, and when the power supplied by the power supply assembly 14 is low, to extend the working time of the riding lawn mower 100 as much as possible, the starting acceleration in each starting mode when the power supplied by the power supply assembly 14 is high (for example, the first power) is higher than the starting acceleration in each starting mode when the power supplied by the power supply assembly 14 is low (for example, the second power). The riding lawn mower includes a power detection module (not shown) for detecting the power supplied by the power supply assembly 14. The power detection module is connected to the power supply assembly 14 and the walking control module 20. If the user selects the first starting mode, the current first starting acceleration in the first starting mode is less than the first starting acceleration in the first starting mode when the power detected by the power detection module is higher than the current power. By analogy, the starting acceleration under the same starting mode can be different due to the power supplied by the power supply assembly 14. The lower the power supply, the less the starting acceleration value under the same starting mode; the higher the power supply, the greater the braking acceleration value under the same braking mode.

[0063] In some embodiments, the riding lawn mower 100 further includes a second operating component 135. The second operating component is configured to send a start signal to start the walking motor 123. The second operating component 135 sends a start signal, and the walking motor 123 starts according to the starting mode corresponding to the operating state of the first operating component 134. The second operating component 135 may include an operating lever, and the operating lever includes a left operating lever 131L and a right operating lever 131R.

[0064] For example, when the left operating lever 131L and the right operating lever 131R are simultaneously pushed out of the neutral position and enter any one of the forward position or the reverse position, the state at this time indicates that the start signal is issued.

[0065] The first operating component 134 is also used to set the braking mode of the walking motor 123; the first operating component also has: a fourth operating state configured to brake the walking motor 123 in the first braking mode, and in the first braking mode, the walking motor brakes at a first braking acceleration; a fifth operating state configured to brake the walking motor in the second braking mode, and in the second braking mode, the walking motor brakes at a second braking acceleration; wherein the second braking acceleration is different from the first braking acceleration.

[0066] By configuring different braking accelerations, different braking modes can be provided. For example,

if the second braking acceleration is greater than the first braking acceleration, when the user needs to brake quickly, the second braking acceleration with a greater braking acceleration can be selected, and when the user needs to brake comfortably, the first braking acceleration with a less braking acceleration can be selected.

[0067] Similarly, the braking acceleration under the same braking mode can also be different according to the power supplied by the power supply assembly 14. The lower the power supply, the less the braking acceleration value under the same braking mode, the higher the power supply, the greater the braking acceleration value under the same braking mode.

[0068] The second operating component 135 is further configured to send a brake signal to brake the walking motor; the walking control module 20 is configured to: after the second operating component 135 sends a start signal, start the walking motor 123 according to the starting mode corresponding to the operating state of the first operating component 131; after the second operating component 132 sends a brake signal, brake the walking motor according to the braking mode corresponding to the operating state of the first operating component 134.

[0069] The walking control module 124 controls the start and brake of the walking motor 123, optionally, the walking control module 124 may also control the normal operation of the walking motor 123, that is, the walking control module 124 may control the whole operation process of the walking motor 123.

[0070] Optionally, the riding lawn mower 100 further includes a brake pedal 136 for the user to mechanically brake the riding lawn mower 100, and the user depresses the brake pedal 136 to make the riding lawn mower 100 slow down and stop.

[0071] As an optional solution, the riding lawn mower 100 further includes a third operating component 137 for making the riding lawn mower 100 enter a ready state. That is, after the operator sits on the seat 15, the third operating component 137 needs to be operated first before starting the walking motor 123 subsequently.

[0072] The third operating component 137 includes: a first trigger 1371 for powering on the walking control module 124; a second trigger 1372 for enabling the walking motor 123 to start, for example, start according to the starting mode set by the first operating component 134. The walking control module 20 is configured to control the walking motor 123 to start after the first trigger 1371 is triggered and then the second trigger 1372 is triggered. That is, only after the first trigger is triggered and then the second trigger is triggered, the walking motor 123 can be controlled to start, for example, the control module starts the walking motor 123 according to the starting mode set by the first operating component 134 and the target speed set by the second operating component 135. Otherwise, if only the third operating component 137 is triggered or the sequence of triggering the first triggering component 1371 and the second triggering component 1372 is different, even if the first operating compo-

nent 134 is provided with a starting mode and the second operating component 135 sends a start signal, the walking motor 123 will not start. Optionally, the first trigger 1331 can also be used to power on the cutting control module and the display module. By providing at least two triggers and their triggering sequence, it is possible to prevent the operator from erroneously triggering the walking motor 123, thereby improving the operational safety of the riding lawn mower 100.

[0073] The walking control module 124 can obtain a trigger state of the first trigger 1371. In some specific embodiments, the first trigger 1371 includes a safety key and a key socket. When the safety key is inserted into the key socket, the first trigger 1371 is triggered. Optionally, a sensing module is provided in the key socket, which can detect whether the safety key is inserted into the key socket, and transmit information to the walking control module 124, thus, the walking control module 124 can obtain the information detected by the sensing module on whether they safety key is inserted into the key socket.

[0074] Optionally, during the walking process of the riding lawn mower 100, if it is detected that the first trigger is not triggered, for example, the safety key is pulled out of the key socket, then control the walking motor 123 to power off or to brake and then power off, and the riding lawn mower 100 enters a low power consumption state. In the low power consumption state, the cutting motor 112 and the walking motor 123 are powered off and stopped, only some display modules can still display, and the controllers in the cutting control module and the walking control module 20 enter the low power consumption state. This avoids accidents caused by abnormal control of the walking motor 123 when the operator pulls out the key by mistake or the key jumps out of the key socket during the walking process of the riding lawn mower 100, thereby improving the driving safety of the riding lawn mower 100.

[0075] The walking control module 124 can obtain a trigger state of the second trigger 1372. In some embodiments, the second trigger 1372 includes a start button, and the user may press the start button to trigger the second member 1372. The second trigger 1372 may be, for example, a signal switch connected to the walking control module 124. The walking control module 124 can obtain the switch state of the signal switch. When the signal switch is triggered to change the switch state, the walking control module 124 detects that the second trigger 1372 is triggered.

[0076] Optionally, during the walking process of the riding lawn mower 100, if the second trigger 1372 is triggered, then control the walking motor 123 to remain in current state or to power off or to brake and then power off, and the riding lawn mower 100 enters a low power consumption state. This avoids accidents caused by abnormal control of the walking motor 123 when the operator accidentally triggers the second trigger 1372 during the walking process of the riding lawn mower 100, there-

by improving the driving safety of the riding lawn mower 100.

[0077] As an optional solution, the operating component further includes a fourth operating component for setting the speed gear of the walking motor 123; the walking control module 124 is configured to: when the walking motor 123 rotates, disable the speed gear setting function of the fourth operating component. Referring to FIG. 13, in some embodiments, the fourth operating component is a plurality of gear setting operation buttons 221 on the operation panel, for setting the speed gear of the walking motor 123. Under different speed gears, the maximum rotational speed of the walking motor 123 is different. Optionally, the higher the speed gear position is, the higher the maximum rotational speed of the walking motor 123. When the walking motor 123 rotates, even if the fourth operating component is operated to change the speed gear position, the speed gear position still retains in the original gear position, and the speed gear setting function of the walking motor 123 is disabled. This avoids the conflict of the current rotational speed of the walking motor 123 and the gear speed set by the operator due to wrong operations during the walking process of the riding lawn mower 100, which affects driving safety.

[0078] Optionally, the walking control module 20 is configured to control the walking motor 123 to stop rotating when the fourth operating component is operated. That is, when the speed gear of the walking motor 123 is set through the fourth operating component, prohibit the operation of the walking motor 123 and thus the walking of the riding lawn mower 100, thereby avoiding the abnormal operation of the walking motor 123.

[0079] Referring to FIG. 5, optionally, the riding lawn mower 100 further includes an operation panel 22, and a plurality of buttons are provided on the operation panel 22, at least a first button and a second button are provided. The first button is configured to control a first function; when the first button is pressed, the first function is triggered. The second button is configured to control a second function; when the second button is pressed, the second function is triggered. When both the first button and the second button are pressed, a third function is triggered. The third function is different from the first function and the second function. Optionally, the operation panel 22 is a touch display screen with a touch function.

[0080] In an embodiment, the first operating component 134 is provided on the operation panel 22, and the operating component includes a first starting mode button 1341, a second starting mode button 1342, and a third starting mode button 1343. For example, a first button is the first starting mode button 1341, and a second button is the second starting mode button 1342. When these two buttons are operated separately, they have different functions. The first starting mode button 1341 is configured to set the first starting acceleration. The second starting mode button 1342 is configured to set the second starting acceleration. When both the first starting mode button 1341 and the second starting mode

button 1342 are pressed, the third function can be triggered. In some embodiments, the third function is configured to adjust the maximum output rotational speed of the walking motor 123. In some specific embodiments, the third function is configured to enable the first braking mode or the second braking mode. In some specific embodiments, the third function can be used to call up a Bluetooth interface. In some specific embodiments, the third function can call up a wireless connection interface and start a cruise control function. In some specific embodiments, call up the USB setting function. The first button, the second button, and the third function generated by the combination of the first button and the second button can all be set by the user according to requirements.

[0081] Optionally, the riding lawn mower 100 further includes a charging interface for connecting an external power source to charge the battery pack inserted into the power supply assembly 14. The charging interface includes: a charging sensing module with a first state and a second state for sensing whether an external power source is connected; in the first state, the external power source is connected to the charging interface; in the second state, the external power source is not connected to the charging interface. The walking control module 124 is configured to: when the charging sensing module is in the first state, the walking control module 124 controls the walking motor 123 to slow down.

[0082] Optionally, the riding lawn mower 100 is provided with a charging interface, into which an external power source can plug, such as a 220V alternating current. When the external power source is plugged into the charging interface, the charging sensing module can sense the plug-in of the external power source. In a specific embodiment, the charging sensing module has a signal switch, which is provided in the charging interface. When the plug of an external power source is plugged into the charging interface, the signal switch is touched by the plug of the power source to change the state, so that the plug-in of the external power source can be sensed. In some specific embodiments, the sensing module includes a detection circuit, which may include a voltage divider resistance. When the external power supply is plugged in, the voltage of the output terminal of the voltage divider resistance changes, so that the plug-in of the external power supply can be detected.

[0083] The walking control module 124 can obtain the status of the sensing module. When the sensing module detects that the external power supply is plugged in, the walking control module 124 controls the walking motor 123 to slow down. Optionally, the walking control module 124 controls the walking motor 123 to brake and decelerate to stop. In other words, when the external power supply is plugged into the charging interface, the walking motor 123 needs to decelerate and stop to prevent damages to the charging interface or the external power socket or other components of the riding lawn mower 100 caused by the riding lawn mower 100 walking while

charging.

[0084] Optionally, the riding lawn mower 100 further includes a cutting control module for controlling the operation of the cutting motor; the cutting control module is configured to control the cutting motor 112 to reduce the speed when the charging sensing module is in the first state. Optionally, control the walking motor 123 to brake and decelerate to stop. In other words, when the external power supply is plugged into the charging interface, the cutting motor 112 needs to decelerate and stop to prevent accidents caused by the riding lawn mower 100 mowing while charging.

[0085] Referring to FIG. 14, in an embodiment, a control system of the walking motors 123 includes a left walking motor control system and a right walking motor control system. The left walking motor control system and right walking motor control system have the same or similar functions and components. Take the left walking motor control system as an example, which mainly includes: a left walking motor control module 124L, a left walking motor drive circuit 127L, a left operation sensing module 132L, a left walking motor speed detection module 128L, and a left walking motor 123L.

[0086] The left walking motor control module 124L is configured to control the operation of the left walking motor 123L; it is connected with the left operation sensing module 132L, the left walking motor speed detection module 128L, and the left walking motor drive circuit 127L, and is configured to adjust a control amount of the left walking motor 123L according to the detection signals of the left operation sensing module 132L and the left walking motor speed detection module 128L, and output a control signal to the left walking motor drive circuit 127L, thereby controlling the left walking motor drive circuit 127L to make the left walking motor drive circuit 127L drive the left walking motor 123L to reach or substantially reach the target rotational speed set by the left operating mechanism 131L as soon as possible. The control amount of the left walking motor 123L includes the input voltage and/or the input current of the left walking motor 123L.

[0087] The left operation sensing module 132L is coupled with the left operating mechanism 131L, and configured to detect the operating state of the left operating mechanism 131L, and output which to the left walking motor control module 124L, so that the left walking motor control module 124L can obtain the target rotational speed and direction of the left walking motor 123L according to the detected result of the left operation sensing module 132L. In this embodiment, the operating mechanism 131 may be the first operating component 134 as described above, which includes a left operating lever 131L and a right operating lever 131R, and the left operation sensing module 132L is coupled with the left operating lever 131L for detecting the position of the left operating lever 131L. The left operation sensing module 132L includes an angle sensor or a position sensor for detecting a rotated angle or a rotated position of the left

operating lever 131L.

[0088] The left walking motor speed detection module 128L is coupled with the left walking motor 123L, and configured to detect the actual rotational speed of the left walking motor 123L. As an alternative, the left walking motor speed detection module 128L includes a speed detection sensor, which is arranged near or inside the left walking motor 123L to obtain the actual rotational speed of the left walking motor 123L; for example, a photoelectric sensor installed near the left walking motor 123L to obtain the actual rotational speed of the left walking motor 123L; for another example, a Hall sensor arranged near the rotor inside the left walking motor 123L to obtain the actual rotational speed of the left walking motor 123L according to the rotational speed of the rotor.

[0089] However, in some cases, for example, when the walking motor 123 operates at high speed and/or high temperature, or the first walking wheel 121 runs at high speed and/or high temperature, or the riding lawn mower operates at high temperature, the detection accuracy of the sensor will be affected, the speed detection sensor can even be invalid. Therefore, in order to solve this problem, in another implementation, the left walking motor speed detection module 128L does not include a sensor, and the left walking motor speed detection module 128L uses a brushless walking motor 123. The electrical signal output by the left walking motor speed detection module 128L is a periodically changed back electromotive force, thus, by detecting the current and/or voltage of the left walking motor 123L, the periodic change of the left walking motor speed detection module 128L can be obtained from the zero-crossing point of the back electromotive force, thereby, the actual rotational speed of the left walking motor speed detection module 128L can be obtained. In this way, there is no need for a sensor to detect the actual rotational speed of the left walking motor speed detection module 128L, which reduces cost, meanwhile, the detection accuracy is not affected by high speed or temperature, and the whole machine structure is more compact.

[0090] The left walking motor drive circuit 127L is connected to the left walking motor control module 124L and the left walking motor 123L, and configured to control the operation of the left walking motor 123L according to the signal output by the left walking motor control module 124L.

[0091] Optionally, the left walking motor 123L may be connected to the left drive wheel 122L through a deceleration device. The output speed of the left walking motor 123L is decelerated by the deceleration device 41L and then output to the left drive wheel 122L to drive the left drive wheel 122L to rotate. The torque of the left walking motor 123L is transmitted to the left drive wheel 122L through the deceleration device to drive the left drive wheel 122L. In other embodiments, the left walking motor 123L and the left drive wheel 122L are directly connected.

[0092] The right motor control system mainly includes: a right walking motor control module 124R, a right oper-

ation sensing module 132R, a right walking motor speed detection module 128R, a right walking motor drive circuit 127R, and a walking motor 123R. The right walking left motor control system has the same or similar functions and components as the left walking motor control system, so will not be further described herein.

[0093] In the foregoing embodiment, the left walking motor control module 124L, the left operation sensing module 132L, the right walking motor control module 124R, and the right operation sensing module 132R are all connected to the bus 27, and information transmission between the various devices is implemented through the bus. Through the bus 27, the target rotational speed and direction of the left walking motor 123L set by the left operating mechanism 131L detected by the left operation sensing module 132L can be transmitted to the left walking motor control module 124L through the bus 27. Similarly, the target rotational speed and direction of the right walking motor 123R set by the right operating mechanism 24R detected by the right operation sensing module 23R can be transmitted to the right walking motor control module 20R through the bus 27.

[0094] Referring to FIG. 15, in an embodiment, a control system for a walking motor includes: a walking control module 124, a drive circuit 127, a power supply circuit 145, and a speed detection module 128. Since the control systems of the left and the right walking motors 123 have the same or similar functions and components, the control system of this embodiment can be applied to the control system of the left and the right walking motors 123.

[0095] The walking control module 124 is configured to control the running process of the walking motor 123. In some embodiments, the walking control module 124 adopts a dedicated controller, such as some dedicated control chips (for example, MCU, Microcontroller Unit). The power supply circuit 145 is connected to the power supply assembly 14, and the power supply circuit 145 is configured to receive the power from the power supply assembly 14 and convert the power of the power supply assembly 14 into the power at least used by the walking control module 124. The power supply assembly 14 includes a plurality of aforementioned battery packs 141.

[0096] Optionally, the riding lawn mower 100 further includes a drive circuit 127. The drive circuit 127 is electrically connected to the walking control module 124 and the walking motor 123, and controls the operation of the walking motor 123 according to the control signal output by the walking control module 124. In an embodiment, the walking motor 123 is a three-phase brushless motor with three-phase windings, and the drive circuit 127 is electrically connected to the three-phase windings of the walking motor 123. The drive circuit 127 includes power switches, which turn on and off the electrical connection between the power supply assembly 14 and the walking motor 123, and also adjust the current output from the power supply assembly 14 to the walking motor 123 according to different control signals output by the walking control module 124.

[0097] The walking control module 124 is configured to output corresponding drive signals to the drive circuit 127 according to the position of the rotor 1231 of the walking motor 123 to switch the driving state of the drive circuit 127, thereby changing the voltage and/or current applied to the windings of the walking motor 123, so as to generate an alternating magnetic field to drive the rotor to rotate, thereby driving the walking motor 123.

[0098] The position of the rotor 1231 of the walking motor 123 can be obtained by the rotor position detection module 26. The rotor position detection module 26 may include sensors, for example, a plurality of Hall sensors, arranged along the circumferential direction of the rotor 1231 of the walking motor 123. When the rotor 1231 rotates into and out of a predefined range, the signals of the Hall sensors change, and the output signal of the rotor position detection module 26 also changes accordingly. In this way, the detected signal output by the rotor position detection module 26 can be used to determine the position of the rotor 1231 of the walking motor 123. Optionally, the position of the rotor 1231 can also be estimated based on the current of the walking motor 123.

[0099] Optionally, the riding lawn mower 100 further includes a speed detection module 128, which is coupled with the walking motor 123 and configured to detect the actual rotational speed of the walking motor 123. Optionally, the speed detecting module 128 includes a speed detection sensor, which is disposed near or inside the walking motor 123 to obtain the actual speed of the walking motor 123; for example, a photoelectric sensor installed near the walking motor 123 to obtain the actual rotational speed of the walking motor 123; for another example, a Hall sensor arranged near the rotor inside the walking motor 123 to obtain the actual rotational speed of the walking motor 123 according to the rotational speed of the rotor.

[0100] The user controls the rotational speed and direction of the walking motor 123 through the operating mechanism 131. The operating mechanism 131 is configured to set the target speed and the direction of rotation of the walking motor 123, so that the target speed and the direction of the riding lawn mower 100 can be set.

[0101] In an embodiment, the operating mechanism 131 may be the aforementioned second operating component 135, which includes an operating lever arranged on either sides or the periphery of the seat 15. The user controls the riding lawn mower 100 to reach the state corresponding to the target position reached by the operating lever by pushing the operating lever to the target position. In a specific embodiment, the operating mechanism 131 includes operating levers, for example, a left operating lever 131L and a right operating lever 131R, for controlling the left walking motor 123L and the right walking motor 123R respectively, so as to respectively control the two second walking wheels 122.

[0102] The riding lawn mower 100 further includes an operation sensing module 132 for sensing the operating state of the operating mechanism 131. In this embodi-

ment, the operation sensing module 132 is configured to detect the position of the operation lever, and transmit the detected position information of the operation lever to the walking control module 124. The walking control module 124 obtains the target speed, rotation direction, starting or braking, etc. of the corresponding walking motor according to the detected position of the operating lever by calculation or lookup table. When the two walking motors 123 drive the corresponding second walking wheels 122 to rotate at different speeds, a speed difference is generated between the two second walking wheels 122, so that the riding lawn mower 100 realizes steering.

[0103] In a specific embodiment, the left operating lever 131L and the right operating lever 131R each have a forward position, a reverse position, and a neutral position. When the operator sits on the seat 15 and pushes the left operating lever 131L or the right operating lever 131R in the front and rear direction to a certain position in the forward position, the left walking control module 124L or the right walking control module 124R obtain the forward rotational speed of the left walking motor 123L or the right walking motor 123R corresponding to the current position of the left operating lever 131L or the right operating lever 131R detected by the operation sensing module 132 by lookup table, thereby controlling the left walking motor 123L or the right walking motor 123R to operate according to the target state set by the corresponding left operating lever 131L or right operating lever 131R, thus the corresponding walking wheels move forward.

[0104] Similarly, when the operator sits on the seat 15 and pushes the left operating lever 131L or the right operating lever 131R to a certain position in the reverse position, the left walking control module 124L or the right walking control module 124R obtain the reverse rotational speed of the left walking motor 123L or the right walking motor 123R corresponding to the current position of the left operating lever 131L or the right operating lever 131R detected by the operation sensing module 132 by lookup table, thereby controlling the left walking motor 123L or the right walking motor 123R to operate according to the target state set by the corresponding left operating lever 131L or right operating lever 131R, thus the corresponding walking wheels move forward.

[0105] When the operator sits on the seat 15 and simultaneously pushes the left operating lever 131L and the right operating lever 131R outward from the neutral position in the left and right direction, the parking signal is triggered, and the riding lawn mower 100 enters the parking mode. When the operator sits on the seat 15 and pushes the left operating lever 131L or the right operating lever 131R to the neutral position, the walking motor corresponding to that operating lever stops.

[0106] When the left operating lever 131L and the right operating lever 131R reach the same position in the forward position, the left walking motor 123L and the right walking motor 123R of the riding lawn mower 100 follow

the target speed set by the left operating lever 131L and the right operating lever 131R to rotate forwardly, driving the riding lawn mower 100 to move forward in a straight line. When the left operating lever 131L and the right operating lever 131R reach the same position in the reverse position, the left walking motor 123L and the right walking motor 123R of the riding lawn mower 100 follow the target speed set by the left operating lever 131L and the right operating lever 131R to rotate reversely, driving the riding lawn mower 100 go move backward in a straight line. The operating mechanism can also be a combination of a steering wheel and an accelerator.

[0107] When starting, the second operating component 135 is configured to send a start signal to start the walking motor 123. For example, when the left operating lever 131L and the right operating lever 131R are simultaneously pushed away from the front and rear direction to a certain position of the forward position or the reverse position, the operation sensing module 132 senses that the left operating lever 131L and the right operating lever 131R is away from the neutral position, and outputs the current position information of the left operating lever 131L and the right operating lever 131R to the two walking control modules 124. After receiving this information, it is believed that the operator has sent a start signal through the operating mechanism 131; then the two walking control modules 124 respectively obtain the speed and steering of the two walking motors 123 corresponding to the current position information by lookup table or calculation, and start the walking motors 123 according to the starting mode set by the operator through the first operating component 134 before starting.

[0108] When braking, the second operating component 135 is configured to send a brake signal to brake the walking motor 123. As a specific embodiment, when the left operating lever 131L and the right operating lever 131R are simultaneously pushed away from the neutral position to the outermost position in the left and right direction, the operation sensing module 132 senses the current position of the left operating lever 131L and the right operating lever 131R, and outputs the current position information of the left operating lever 131L and the right operating lever 131R to the two walking control modules 124. After receiving this information, it is believed that the operator has sent a brake signal through the operating mechanism 131; then the two walking control modules 124 brake the walking motors 123 according to the braking mode set by the operator through the first operating component 134.

[0109] Referring to FIG. 15, in a specific embodiment, the walking control module 124 includes: a first speed loop 1241, a current distribution unit 1242, a first current loop 1243, a second current loop 1244, a voltage transformation unit 1245, a current transformation unit 1247 and a PWM signal generation unit 1246.

[0110] The first speed loop 1241 is coupled and connected with a target speed detection module 129 and a speed detection module 128. The first speed loop 201

acquires the target rotational speed n_0 of the walking motor 123 set by the user through the operating mechanism 131 detected by the target speed detection module 129 and the actual rotational speed n of the walking motor 123 detected by the speed detection module 128. The operation sensing module 23 is coupled with the operating mechanism. In this embodiment, the operation sensing module 132 is coupled with the operating lever, and configured to detect the position or the angle of rotation of the operating lever. The operation sensing module 132 may include a position sensor, such as a magnetic sensor.

[0111] The first speed loop 1241 is configured to generate a target current i_{s0} according to the target rotational speed n_0 and the actual rotational speed n of the walking motor 123. Alternatively, the first speed loop 1241 can generate a target current i_{s0} through comparison and adjustment according to the target rotational speed n_0 and the actual rotational speed n of the walking motor 123. The target current i_{s0} is used to make the actual rotational speed n of the walking motor 123 approach the target rotational speed n_0 . The first speed loop includes a comparison and adjustment unit (not shown), and the adjustment unit may be a PI adjustment unit.

[0112] The current distribution unit 1242 is connected to the first speed loop 1241, and is used to distribute a direct axis target current i_{d0} and a quadrature axis target current i_{q0} according to the target current i_{s0} .

[0113] Referring to FIG. 16, the direct axis and the quadrature axis form a direct axis - quadrature axis coordinate system. The direct axis - quadrature axis coordinate system establishes a coordinate system on the rotor of the walking motor 123. This coordinate system rotates synchronously with the rotor. The direction of the rotor magnetic field is the direct axis, and the direction perpendicular to the rotor magnetic field is the quadrature axis. The direct axis target current i_{d0} and the direct axis are in the same direction, the quadrature axis target current i_{q0} and the quadrature axis are in the same direction, wherein the quadrature axis target current i_{q0} is the excitation current, which is used to control the torque and generate a torque perpendicular to the rotor to drive the rotor to rotate. The quadrature axis target current i_{q0} and the direct axis target current i_{d0} can be obtained by calculation, or can be set directly.

[0114] When a voltage is applied to the walking motor 123, the stator can generate current, so that the walking motor 123 generates electromagnetic torque T_e . The electromagnetic torque T_e of the walking motor 123 can be obtained by the following formula:

$$T_e = 1.5P_n[\Psi_f * i_{q0} + (L_d - L_q) * i_d * i_q],$$

wherein Ψ_f is the rotor flux linkage, i_q is the quadrature axis current, i_d is the direct axis current, L_d is the direct axis inductance of the stator windings, L_q is the quadrature axis inductance of the stator windings, P_n is the

number of magnetic pole pairs, and Ψ_f is the flux linkage constant of a walking motor 123.

[0115] The control module 124 can control the current loaded on the stator by controlling the three-phase voltage U_u, U_v, U_w loaded on the walking motor 123 according to the rotational speed of the walking motor 123, the current of the walking motor 123, and the position of the rotor to make the stator windings generate a stator current space vector i_{s0} ; the stator current space vector i_{s0} and the stator flux linkage space vector Ψ_s are of the same direction, and the stator current space vector i_{s0} is the target current i_{s0} . The target current i_{s0} as mentioned above can be distributed by the current distribution unit 1242 as the direct axis target current i_{d0} and the quadrature axis target current i_{q0} . The control module 124 can control the angle β between the stator flux linkage Ψ_s and the rotor flux linkage Ψ_f by separately controlling the quadrature axis current i_q and the direct axis current i_d , so as to change electromagnetic torque T_e output by walking motor 123, and thereby, to control the acceleration of the walking motor, including starting acceleration and braking acceleration. In this way, under different starting modes, output different starting accelerations; and under different braking modes, output different braking accelerations.

[0116] The direct axis target current i_{d0} and the quadrature axis target current i_{q0} distributed by the current distribution unit 1242 according to the target current i_{s0} can cause the rotor of the walking motor 123 to generate different electromagnetic torque T_e , so that the walking motor 123 can reach the target rotational speed n_0 of the walking motor 123 set by the user by the operating mechanism 131 in different accelerations. Different accelerations include starting accelerations and braking accelerations.

[0117] The current transformation unit 1247 obtains the three-phase currents i_u, i_v, i_w , and performs current transformation to convert the three-phase currents i_u, i_v, i_w into two-phase currents, which are the direct axis actual current i_d and the quadrature axis actual current i_q , respectively. The current detection module 29 transmits the detected three-phase currents i_u, i_v, i_w in the actual operation of the walking motor 123 to the current transformation unit 1247 in the control module 124. Optionally, the current transformation unit 1247 includes Park conversion and Clark conversion.

[0118] The first current loop 1243 is connected to the current distribution unit 1242 and the current transformation unit 1247 to obtain the direct axis target current i_{d0} and the direct axis actual current i_d , and generate a first voltage adjustment amount U_d according to the direct axis target current i_{d0} and the direct axis actual current i_d . The first voltage adjustment amount U_d can make the direct axis actual current i_d approach the direct axis target current i_{d0} as soon as possible. The first current loop 1243 includes a comparison and adjustment unit (not shown), the adjustment unit may be PI adjustment, and the first current loop 1243 includes comparing the direct

axis target current i_{d0} and the direct axis actual current i_d , and performing the PI adjustment according to the comparison result to generate the first voltage adjustment amount U_d .

[0119] The second current loop 1244 is connected with the current distribution unit 1242 and the current transformation unit 1247 to obtain the quadrature axis target current i_{q0} and the quadrature axis actual current i_q , and generate a second voltage adjustment amount U_q according to the quadrature axis target current i_{q0} and the quadrature axis actual current i_q . The second voltage adjustment amount U_q can make the quadrature axis actual current i_q approach the quadrature axis target current i_{q0} . The second current loop 1244 includes a comparison and adjustment unit (not shown), the adjustment unit may be PI adjustment, and the second current loop 1244 includes comparing the quadrature axis target current i_{q0} and the quadrature axis actual current i_q , and performing the PI adjustment according to the comparison result to generate the second voltage adjustment amount U_q .

[0120] The above-mentioned first voltage adjustment amount U_d and second voltage adjustment amount U_q need to be converted into control signals for controlling the drive circuit 127 after some transformation and calculation. The first voltage adjustment amount U_d and the second voltage adjustment amount U_q are sent to the control signal generation unit for transformation and calculation. In this embodiment, the control signal generation unit includes a voltage transformation unit 1245 and a PWM signal generation unit 1246.

[0121] The voltage transformation unit 1245 is connected to the first current loop 1243 and the second current loop 1244 to obtain the first voltage adjustment amount U_d and the second voltage adjustment amount U_q , and the position of the rotor of the walking motor 123 from the rotor position detection module 26, and convert the first voltage adjustment quantity U_d and the second voltage adjustment quantity U_q into intermediate amounts U_a and U_b related to the three-phase voltage U_u, U_v, U_w applied to the walking motor 123, and output them to the PWM signal generation unit 1246. The PWM signal generation unit 206 generates PWM signals for controlling the switching elements of the driving circuit 127 according to the intermediate amounts U_a and U_b , so that the power supply assembly 14 can output three-phase voltages U_u, U_v, U_w to be applied to the windings of the walking motor 123. U_u, U_v, U_w are three-phase symmetrical sine wave voltages or saddle wave voltages, and the three-phase voltages U_u, U_v, U_w form a 120° phase difference with each other. Optionally, the voltage transformation unit 1245 includes Park inverse transform and Clark inverse transform.

[0122] Using the above-mentioned control module 124, this embodiment adopts the following control methods:

The current transformation unit 1247 obtains the three-phase currents i_u, i_v, i_w detected by the current detection

module 29 and the rotor position information detected by the rotor position detection module 26, and performs current transformation to convert the three-phase currents i_u, i_v, i_w into two-phase currents, which are the direct axis actual current i_d and the quadrature axis actual current i_q , respectively. The first current loop 203 obtains the above-mentioned direct axis target current i_{d0} and direct axis actual current i_d , and generates the first voltage adjustment amount U_d according to the direct axis target current i_{d0} and the quadrature axis actual current i_d . The second current loop 204 obtains the above-mentioned quadrature axis target current i_{q0} and direct axis actual current i_q , and generates the second voltage adjustment amount U_q according to the quadrature axis target current i_{q0} and the quadrature axis actual current i_q . The voltage transformation unit 1245 obtains the first voltage adjustment amount U_d , the second voltage adjustment amount U_q , and the rotor position from the rotor position detection module 26, and converts the first voltage adjustment amount U_d and the second voltage adjustment amount U_q into intermediate amounts U_a and U_b related to the three-phase voltages U_u, U_v, U_w applied to the walking motor 123, and outputs them to the PWM signal generation unit 1246. The PWM signal generation unit 206 generates PWM signals according to the intermediate amounts U_a and U_b for controlling the switching elements of the drive circuit 127, thereby the power supply assembly 14 outputs three-phase voltages U_u, U_v, U_w to be applied to the windings of the walking motor 123. In this embodiment, the three-phase voltages U_u, U_v, U_w are three-phase symmetrical sine wave voltages or saddle wave voltages, and the three-phase voltages U_u, U_v, U_w form a 120° phase difference with each other.

[0123] Referring to FIG. 14, the riding lawn mower 100 further includes a feedback circuit 28 for feeding back the electric energy generated by the walking motor 123 to the power supply assembly 14 during the braking process of the walking motor 123. For example, when the walking motor 123 is braking, reduce the speed of the walking motor 123 so that the walking control module 124 outputs a negative current torque component by adjusting the corresponding walking motor 123. At this time, the walking motor 123 outputs a negative torque and generates electricity. The current generated by the walking motor 123 is fed back to the power supply assembly 14 through the feedback circuit 28.

[0124] Optionally, the feedback circuit 28 includes a power supply voltage detection module 281 for detecting the voltage of the battery packs 141. The walking control module 124 is configured to: obtain the voltage detection value from the power supply voltage detection module 281; when the voltage detection value is greater than or equal to a predefined threshold, cut off the electrical connection between the walking motor 123 and the power supply assembly 14. Optionally, the predefined threshold is the rated voltage of the battery packs. In other words, when it is detected that one or more battery packs 141

are substantially fully charged, i.e., in a fully charged state, the electrical connection between the walking motor 123 and the power supply assembly 14 is cut off. In this way, the current generated by the braking of the walking motor 123 will not be used for the battery packs 141 that are basically fully charged, i.e., in a fully charged state, so as to prevent the battery packs 141 from being overcharged.

[0125] In some specific embodiments, the walking control module 124 is configured to: cut off the electrical connection between the walking motor 123 and the battery packs 141, and short-circuit the windings of the walking motor 123; that is, control the drive circuit 127 through the walking control module 124 to turn on all upper bridge switching elements (VT1, VT3, VT5) or all lower bridge switching elements (VT2, VT4, VT6), so that the ends of the phase windings connected to the neutral point are connected to each other, so that the windings of each phase are short-circuited. In this way, the resistance of the windings is used to consume electric energy, so that the electric energy generated by the walking motor 123 will not damage other electronic components.

[0126] In a specific embodiment, the feedback circuit 28 includes at least one electronic switch, which is connected between the power supply assembly 14 and the drive circuit 127. When the voltage detection value detected by the power supply voltage detection module 281 exceeds the predefined threshold, the walking control module 124 controls the electronic switch to turn off. In some embodiments, the feedback circuit 28 includes an electronic switch Q2.

[0127] Optionally, the riding lawn mower 100 further includes a first electronic switch Q1, a second electronic switch Q2, and a unidirectional diode D1. Wherein, the first electronic switch Q1 and the second electronic switch Q2 are connected in series between the power supply assembly 14 and the drive circuit 21, and the unidirectional diode D1 is connected in parallel with the first electronic switch. The unidirectional diode D1 is configured to allow the current from the walking motor 123 flow to the power supply assembly 14.

[0128] When the power supply assembly 14 is required to supply power to the walking motor 123, the first electronic switch Q1 and the second electronic switch Q2 are both turned on, and the power supply assembly 14 can supply power to the walking motor 123 through the first electronic switch Q1 and the second electronic switch Q2. When braking, the first electronic switch Q1 is turned off, whereas the second electronic switch Q2 is kept on. The current generated by the walking motor 123 can flow to the power supply assembly 14 through the second electronic switch Q2 and the unidirectional diode D1. When the voltage of one or more battery packs detected by the power supply voltage detection module 281 exceeds the predefined threshold, the second electronic switch Q2 is turned off to cut off the electrical connection between the battery pack 141 and the walking motor 123, so that the current generated by the walking motor 123

no longer flows to the power supply assembly 14.

[0129] Optionally, the feedback circuit 28 further includes a power supply current detection module 282 for detecting whether there is current flowing from the walking motor 123 to the power supply assembly 14. The walking control module 124 is configured to: obtain the voltage detection value from the power supply voltage detection module 281; determine whether there is a current flowing from the walking motor 123 to the power supply assembly 14; if the voltage detection value is greater than or equal to a predefined threshold and there is a current flowing from the walking motor 123 to the power supply assembly 14, cut off the electrical connection between the walking motor 123 and the power supply assembly 14. Optionally, when the electrical connection between the walking motor 123 and the power supply assembly is cut off, short-circuit the windings of the walking motor 123. By adding the power supply current detection module 282 to determine whether the walking motor 123 is in the braking state or the driving state, the walking motor 123 is prevented from accidentally entering the energy recovery state in the driving state.

[0130] In some specific embodiments, the operating component 13 is at least used to output a parking signal to trigger the riding lawn mower 100 to enter the parking mode. For example, the operating component 13 is also used to output an acceleration signal to trigger the riding lawn mower 100 to exit the parking mode. The operating component 13 can also be used for the user to set the target speed and the traveling direction of the riding lawn mower 100. In other words, the operating component 13 can be operated for the user to set the walking state of the riding lawn mower 100 and to trigger the riding lawn mower 100 to enter and exit the parking mode.

[0131] In some embodiments, the operating component 13 includes a brake pedal 136 for the user to perform brake control on the riding lawn mower 100. Optionally, the brake pedal 136 can output a parking signal to trigger the riding lawn mower 100 to enter the parking mode when it is stepped on.

[0132] In some embodiments, the operation sensing module 132 is configured to detect the position of the operating lever 131, and send the detected position information of the operating lever 131 to the walking control module 124. The walking control module 124 obtains the target speed and direction of rotation of the walking motor 123 corresponding to the detected position of the operating lever 131 through calculation or lookup table, as well as commands on entering and exiting the parking mode.

[0133] For example, when the user pushes the operating lever 131 forward to reach a certain position, based on the position reached by the forward movement of the operating lever 131 as detected by the operation sensing module 132, the walking control module 124 obtains the forward rotational speed of the walking motor 123 by lookup table. When the user pushes the operating lever 131 backward to reach a certain position, based on the

position reached by the forward movement of the operating lever 131, as detected by the operation sensing module 132, the walking control module 124 obtains the reverse rotational speed of the walking motor 123 by lookup table.

[0134] The walking control module 124 controls the rotational speed and steering of the walking motor 123 according to the position information of the operating lever 131. The walking motor 123 drives the second walking wheel 122 to rotate, thereby controlling the traveling direction, traveling speed, entering and exiting the parking mode of the riding lawn mower 100, so as to allow the user to control the walking of the riding lawn mower 100. Optionally, the operating component 13 may also be implemented as other control devices such as pedals, switches, handles, etc., which allow the user to operate the riding lawn mower 100. The operating component 13 may also be a control panel, which includes a plurality of switches, wherein different switches correspond to different control commands. The user inputs different control commands through the switches to control the walking motor 123 of the walking assembly 12.

[0135] The walking control module 124 is configured to control the running process of the walking motor 123. In some embodiments, the walking control module 124 adopts a dedicated controller, such as some dedicated control chips (for example, MCU, Microcontroller Unit). The power supply circuit 145 is connected to the power supply assembly 14, and the power supply circuit 145 is configured to receive the power from the power supply assembly 14 and convert the power from the power supply assembly 14 into the power at least used by the walking control module 124.

[0136] Optionally, the riding lawn mower 100 further includes a drive circuit 127. The drive circuit 127 is electrically connected to the walking control module 124 and the walking motor 123, which controls the walking motor 123 to operate based on the control signals output from the walking control module 124. In an embodiment, the walking motor 123 is a three-phase motor with three-phase windings, and the drive circuit 21 is electrically connected to the three-phase windings of the walking motor 123. The drive circuit 127 includes power switches, which turn on and off the electrical connection between the power supply assembly 14 and the walking motor 123, and also adjust the current output from the power supply assembly 14 to the walking motor 123 according to different control signals output by the walking control module 124.

[0137] The walking control module 124 is configured to output corresponding drive signals to the drive circuit 21 according to the position of the rotor 1231 of the walking motor 123 to switch the driving state of the drive circuit 127, thereby changing the voltage and/or current applied to the windings of the walking motor 123, so as to generate an alternating magnetic field to drive the rotor to rotate, thereby driving the walking motor 123.

[0138] The position of the rotor 1231 of the walking

motor 123 can be obtained by the rotor position detection module 26. The rotor position detection module 26 may include sensors, for example, a plurality of Hall sensors, arranged along the circumferential direction of the rotor 1231 of the walking motor 123. When the rotor 1231 rotates into and out of a predefined range, the signals of the Hall sensors change, and the output signal of the rotor position detection module 26 also changes accordingly. In this way, the detected signal output by the rotor position detection module 26 can be used to determine the position of the rotor 1231 of the motor. Optionally, the position of the rotor 1231 can also be estimated based on the current of the motor.

[0139] The riding lawn mower 100 further includes a speed detection module 128, which is coupled with the walking motor 123 and configured to detect the actual rotational speed of the walking motor 123. Optionally, the speed detecting module 128 includes a speed detection sensor, which is disposed near or inside the walking motor 123 to obtain the actual speed of the walking motor 123; for example, a photoelectric sensor installed near the walking motor 123 to obtain the actual rotational speed of the walking motor 123; for another example, a Hall sensor arranged near the rotor inside the walking motor 123 to obtain the actual rotational speed of the walking motor 123 according to the rotational speed of the rotor.

[0140] However, in some cases, for example, the walking motor 123 operates at high speed and/or high temperature, or the second walking wheels 122 runs at high speed and/or high temperature, or the riding lawn mower operates at high temperature, the detection accuracy of the sensor will be affected, the speed detection sensor can even be invalid. Therefore, in order to solve this problem, in another implementation, the speed detection module 128 does not include a sensor, but through the electrical signal output by the walking motor 123. For example, by detecting the current of the walking motor 123, the periodic change of the walking motor 123 can be obtained from the zero-crossing point of the back electromotive force of the walking motor 123; thereby, the actual rotational speed of the walking motor 123 can be obtained. In this way, there is no need for a sensor to detect the actual rotational speed of the walking motor 123, which reduces cost, meanwhile, the detection accuracy is not affected by high speed or temperature, and the whole machine structure is more compact.

[0141] The riding lawn mower 100 has a parking mode, and the user sends a parking signal through the operating component 13 to trigger the riding lawn mower 100 to enter the parking mode. In the embodiment that makes use of the operating lever 131, the user pushes the operating lever 131 to the parking position to issue a parking signal to trigger the parking mode. The operation sensing module 132 detects that the operation lever 131 is in the parking position, and the detected information is sent to the walking control module 124. The walking control module 124 controls the walking motor 123 to realize parking.

In the embodiment that two operating levers respectively control two walking motors 123, the user issues a parking command by pushing both operating levers 131 to the parking position.

[0142] The walking control module 124 is configured to: when the riding lawn mower 100 enters the parking mode, determine whether the rotational speed of the walking motor 123 is less than or equal to a predefined speed threshold; when it is determined that the rotational speed of the walking motor 123 is less than or equal to the predefined speed, a first torque that is opposite to the tendency of rotation of the walking motor 123 is applied to the walking motor 123. The first torque is configured to make the riding lawn mower stand still in one position, thereby realizing the automatic parking of the riding lawn mower. For example, the first torque is configured to make the riding lawn mower 100 stand still at the position when it enters the parking mode.

[0143] For example, when the riding lawn mower 100 is walking on a ramp, the riding lawn mower 100 is subjected to a vertically downward gravity force, which causes the riding lawn mower 100 to have a tendency to slide down the ramp. If the user sends a parking signal through the operating component 13, the riding lawn mower 100 enters the parking mode, and the walking motor 123 performs mechanical or electronic braking to decelerate, or the walking motor 123 stops freely to decelerate. The speed detection module 128 detects and sends the actual rotational speed of the walking motor 123 to the walking control module 124. When it is determined that the actual rotational speed of the walking motor 123 is less than or equal to the predefined speed threshold, that is, after the rotational speed of the walking motor 123 drops to a certain value, the walking control module 124 applies a first torque that is opposite to the tendency of rotation of the walking motor 123. The first torque has equal magnitude and opposite direction to the external force torque of the riding lawn mower 100 that causes the riding lawn mower 100 to have a tendency to slide. In the embodiment in which the riding lawn mower 100 enters the parking mode while walking on the ramp, the direction of the first torque is upward along the ramp. In this way, due to the balance of torque, the walking motor 123 will eventually be locked in a certain position, so that the riding lawn mower 100 is stationary in one position. For example, the first torque is configured to make the riding lawn mower 100 stand still at the position when it enters the parking mode.

[0144] Optionally, after determining that the rotational speed of the walking motor 123 is less than or equal to the predefined speed threshold, the walking control module 124 controls the power supply assembly 14 to output a first current to the walking motor 123, and the first current causes the walking motor 123 to generate the first torque. In an embodiment, the walking control module 124 outputs a control signal to the drive circuit 21, and the drive circuit 127 adjusts the magnitude and direction of the first current, so that the walking motor 123 gener-

ates the first torque.

[0145] In a specific implementation, the walking control module 124 is configured to: after determining that the rotational speed of the walking motor 123 is less than or equal to the predefined speed threshold, the rotor position detection module detects the current position of the rotor 1231 of the walking motor 123, the walking control module 124 selects the current position of the rotor 1231 of the walking motor 123 as the reference position. In this way, when the rotor 1231 deviates from the reference position, the walking control module 124 can compare the deviated position of the rotor 1231 with the reference position to determine the direction in which the rotor 123 deviates from the reference position, thereby determining the tendency of rotation of the walking motor 123, and the tendency of slide of the riding lawn mower 100.

[0146] After the rotor 1231 deviates from the reference position, the power supply assembly 14 is controlled to output the first current to the walking motor 123 to cause the walking motor 123 to generate the first torque. The first torque is configured to return the rotor 1231 of the walking motor 123 back to the reference position, thereby making the riding lawn mower 100 to stand still at one position, for example, the riding lawn mower 100 can stand still at the position when the riding lawn mower 100 enters the parking mode.

[0147] The operating component 13 is also used to output an acceleration signal to trigger the riding lawn mower to exit the parking mode. The walking control module 124 is configured to: after the operating component 13 sends out the acceleration signal, determine whether the direction of the second torque to be generated by the walking motor 123 corresponding to the acceleration signal is the same as the direction of the first torque; if the direction of the second torque is the same as the direction of the first torque, then determine whether the second torque is greater than or equal to the first torque; if it is determined that the second torque is greater than or equal to the first torque, control the riding lawn mower 100 to exit the parking mode.

[0148] In other words, if you want the riding lawn mower 100 to start walking again, you need to operate the operating component 13 to input an acceleration signal. If the direction of acceleration is the same as the direction of the current parking torque of the walking motor 123, this acceleration signal is not used directly to control the operation of the walking motor 123, but the second torque corresponding to the acceleration signal needs to be calculated. If the second torque is greater than or equal to the first torque for parking the riding lawn mower 100, the parking mode is exited and the walking motor 123 is controlled to operate according to the acceleration signal. If the second torque is less than the first torque, remain in the parking mode. The advantage is: the riding lawn mower 100 can only be released from the parking mode when the acceleration torque can overcome the external force that causes it to slide downward, so as to prevent the riding lawn mower 100 from sliding down the ramp

due to insufficient acceleration torque.

[0149] The operating component 13 is also used to set the target speed of the walking motor 123. After exiting the parking mode, the walking control module 124 controls the walking motor 123 to run at the target speed according to the target speed set by the operating component 13.

[0150] In an embodiment, when the direction of the second torque is opposite to the direction of the first torque, that is, when the user expects the riding lawn mower 100 to walk downhill, there are two cases including uphill parking and reversing, and downhill parking and forwarding. In both cases, the direction of the first torque for parking is upward, and the direction of the second torque corresponding to the acceleration signal is downward, that is, the direction of the second torque is opposite to the direction of the first torque. In this case, the walking control module 124 can control the riding lawn mower 100 to directly exit the parking mode to control the riding lawn mower 100 according to the target speed and direction set by the operating component.

[0151] In another embodiment, using the operating lever 131, when the direction of the second torque direction is opposite to the first torque, the parking mode is not directly exited. It is also necessary to determine whether the change of position after leaving the parking position reaches a predefined threshold, and if so, exit the parking mode; if not, remain in the parking mode. The advantage is to prevent exiting the parking mode due to wrong operations by the driver, wherein frequent start and jitter of the riding lawn mower 100 affects user experience and driving safety.

[0152] The operating lever 131 can be pushed to the parking position to send out the parking signal and to leave the parking position to send out the acceleration signal. Optionally, when the operating lever 131 is opened outward in the left and right direction of the driver, the current state of the operating lever 131 represents the parking signal. When the operating lever 131 is restored from the outwardly opened position to the neutral position or any position of the forward position or the reverse position, the current state of the operating lever 131 represents an acceleration signal.

[0153] In this embodiment, if the change of position of the operating lever 131 after leaving the parking position reaches the predefined threshold, the riding lawn mower 100 is controlled to exit the parking mode. For example, if the operating lever 131 reaches any speed position of the forward position or the reverse position from the parking position, if the angle change of the operating lever 131 reaches a predefined threshold, the riding lawn mower 100 is controlled to exit the parking mode; if the angle change of the operating lever 131 does not reach the predefined threshold, the riding lawn mower 100 is still maintained in the parking mode.

[0154] When the riding lawn mower 100 is parked on a flat ground, it can still be parked according to the parking control method described above, and the first torque ap-

plied to the walking motor is zero at this time.

[0155] Referring to FIG. 17, a control method of the riding lawn mower 100 includes:

5 Step S10: the riding lawn mower is in operation;
The walking control module 124 controls the riding lawn mower 100 to operate normally, for example, uphill or downhill.

10 Step S11: determine whether the riding lawn mower needs to enter the parking mode;

For example, when parking is needed, the user sends a parking signal by operating the operating component 13 to trigger the riding lawn mower 100 to enter the parking mode. As described above, in the embodiment using the operating lever 131, the user sends a parking signal to trigger the parking mode by pushing the operating lever 131 to the parking position. The operation sensing module 132 detects that the operating lever 131 is in the parking position and sends the detected position information to the walking control module 124. The walking control module 124 controls the walking motor 123 to realize parking. In the embodiment in which two operating levers control two walking motors 123 respectively, the user issues a parking command by pushing both operating levers 131 to the parking position. If the operation sensing module 132 does not detect the parking signal that the riding lawn mower 100 needs to enter the parking mode, then go to step S11, and the riding lawn mower 100 continues to maintain the operation state.

25 Step S12: obtain the rotational speed of the walking motor;

When it is determined that the riding lawn mower 100 needs to enter the parking mode, the speed detection module 20 detects the rotational speed of the walking motor and sends it to the walking control module 16, and the walking control module obtains the detected rotational speed of the walking motor 123.

40 Step S13: determine whether the rotational speed of the walking motor is less than or equal to a predefined speed threshold.

The walking control module 16 compares the rotational speed of the walking motor 123 detected by the speed detection module 128 with the predefined speed threshold to determine whether the rotational speed of the walking motor 123 is less than or equal to the predefined speed threshold. If it is determined that the rotational speed of the walking motor 123 is greater than or equal to the predefined speed threshold, then go to step S12 to continue to obtain the rotational speed of the walking motor 123 and determine whether the rotational speed is less than or equal to the predefined speed threshold.

55 Step S14: apply a first torque that is opposite to the tendency of rotation of the walking motor to the walking motor, wherein the first torque is configured to

make the riding lawn mower to stand still in one position.

[0156] After determining that the rotational speed of the walking motor 123 is less than or equal to the predefined speed threshold, apply a first torque that is opposite to the tendency of rotation of the walking motor to the walking motor. For example, the walking control module 124 outputs a control signal to the drive circuit 127, and the drive circuit 127 adjusts the magnitude and direction of the first current, so that the walking motor 123 generates the first torque. The first torque has equal magnitude and opposite direction to the external force torque of the riding lawn mower 100 that causes the riding lawn mower 100 to have a tendency to slide. The first torque is configured to make the riding lawn mower to stand still in one position.

[0157] Step S15: determining whether the riding lawn mower needs to exit the parking mode;

For example, when it is necessary to exit the parking mode and move forward or backward, the user sends an acceleration signal by operating the operating component 13 to trigger the riding lawn mower 100 to exit the parking mode. In the embodiment using the operating lever 131, the user triggers the riding lawn mower 100 to exit the triggered parking mode by pushing the operating lever 131 forward to a certain position or backward to a certain position from the parking position. The operation sensing module 132 detects that the operating lever 131 leaves the parking position to settle in another position, and sends the detected position information to the walking control module 124. The walking control module 124 obtains the rotational direction and rotational speed of the walking motor corresponding to the current position of the operation lever 131 by lookup table or calculation according to the detected position information of the operation lever 131. If the signal that the riding lawn mower 100 needs to exit the parking mode is not detected, then go to step S15 to continue to determine whether the riding lawn mower 100 needs to exit the parking mode, while the riding lawn mower 100 remains in the parking mode.

[0158] Step S16: determine whether the direction of acceleration is the same as the direction of the first torque;

The acceleration signal sent by the user through the operating component 13 includes setting the target direction and target speed of the walking motor 123, thereby controlling the riding lawn mower 100 to operate in accordance with the set target direction and target speed of the walking motor 123. The acceleration signal corresponds to the second torque that the walking motor 123 needs to generate, wherein the second torque enables the riding lawn mower 100 to quickly reach the traveling speed of the walking motor 123 that the user sets. The walking control module 124 can obtain the state of the operating component 13 to decide the direction of acceleration of the riding lawn mower 100 according to the state of the operating component, and determine whether the direc-

tion of acceleration of the riding lawn mower 100 is the same as the direction of the first torque. If yes, then go to step S17, otherwise go to step S18 to exit the parking mode directly. In the embodiment using the operating lever 131, the walking control module 124 obtains the target speed and target direction of the walking motor 123 corresponding to the current position of the operating lever 131 as detected by the target state detection module 18, and determines the direction of acceleration according to the target speed and target direction.

[0159] Step S17: determine whether the acceleration torque is greater than or equal to the first torque;

The walking control module 16 can calculate an acceleration torque according to the above-mentioned target speed of the walking motor 123 set by the operating component 13, and the acceleration torque is the second torque. The walking control module 124 determines whether the acceleration torque is greater than or equal to the second torque. If the acceleration torque is greater than or equal to the first torque, then go to step S19; otherwise, go to step S18 to keep the riding lawn mower 100 in the parking mode.

[0160] Step S18: remain the parking mode.

[0161] If it is determined that the acceleration torque is less than the first torque, the riding lawn mower 100 is kept in the parking mode.

[0162] Step S19: the riding lawn mower exits the parking mode.

[0163] If it is determined that the acceleration torque is greater than or equal to the first torque, the riding lawn mower exits the parking mode, and the walking control module 124 controls the the target speed and direction of the operation of the walking motor 123 according to the target speed and direction of the walking motor 123 set by the operating component 13.

[0164] Referring to FIG. 18, in another embodiment of the control method of the riding lawn mower, the operating component 13 of the riding lawn mower 100 includes an operating lever 131, wherein the lever 131 may be a hand push operating lever as shown in FIGS. 1-2, or a foot-stepping accelerator pedal, or a forward pedal and a reverse pedal.

[0165] The control method of the riding lawn mower in this embodiment includes the following steps, wherein steps S20 to S25 are the same as or similar to the foregoing embodiment, and will not be repeated herein. The difference is that, in the present embodiment, after it is determined that the direction of acceleration is not the same as the direction of the first torque, i.e., the direction of the second torque corresponding to the acceleration signal is opposite to the direction of the first torque, instead of directly exiting the parking mode, a check needs to be performed to determine whether the change of position of the operating lever from the parking position exceeds a predefined threshold. The steps are as follows:

Step S20 to Step S25: the same as step S10 to step S25, and will not be repeated herein.

Step S26: determine whether the direction of acceleration is the same as direction of the first torque.

[0166] The acceleration signal sent by the user through the operating component 13 corresponds to the second torque that the walking motor 123 needs to generate, and the second torque can make the riding lawn mower 100 quickly reach the walking speed of the walking motor 123 that the user needs to set. The walking control module 124 can obtain the state of the operating component 13 to determine the direction of acceleration of the riding lawn mower 100 according to the state of the operating component, and determine whether the direction of acceleration of the riding lawn mower 100 is the same as the direction of the first torque, if yes, go to step S27, otherwise go to step S28.

[0167] Step S27: determine whether the acceleration torque is greater than or equal to the first torque; The walking control module 16 determines whether the acceleration torque is greater than or equal to the second torque. If the acceleration torque is greater than or equal to the first torque, go to step S30; otherwise, go to step S29 to keep the riding lawn mower 100 in the parking mode.

[0168] Step S28: determine whether the change of position of the operating lever exceeds a predefined threshold;

If it is determined that the direction of acceleration is not the same as the direction of the first torque, that is, the direction of the second torque corresponding to the acceleration signal is opposite to the direction of the first torque, it is determined whether the change of position of the operating lever 131 from the parking position exceeds the predefined threshold, if yes then go to step S30, exit the parking mode, if not, go to step S29, remain in the parking mode.

[0169] Step S29: remain in the parking mode.

[0170] Step S291: the riding lawn mower exits the parking mode.

[0171] The riding lawn mower exits the parking mode, the walking control module 124 controls the the target speed and direction of the operation of the walking motor 123 according to the target speed and direction of the walking motor 123 set by the operating component 13.

[0172] The riding lawn mower 100 of the present invention will slide down when starting up upwards on the ramp, which improves driving safety of the riding lawn mower, and also prevents frequent start due to touching the operating lever by mistake when starting up downwards on the ramp, thereby reducing jitter and improving user experience and driving safety.

[0173] In some cases, the riding lawn mower 100 only needs to brake and decelerate without parking, and in other cases, the automatic parking function is triggered after the braking deceleration reaches a certain speed threshold. The riding lawn mower 100 of the present invention has at least two different braking modes, which can adapt to different situations, providing a good user

experience and better safety.

[0174] In some embodiments, the walking control module 124 of the riding lawn mower 100 is also used to control the braking of the walking motor 123. For example, when the walking control module 124 receives a brake signal for triggering braking, it controls the walking motor 123 to brake. There are many kinds of brake signals, and there are many kinds of braking modes.

[0175] In some embodiments, the riding lawn mower 100 includes a brake pedal 136 for triggering the brake of the walking motor 123 of the riding lawn mower. Is an embodiment, the user depresses the brake pedal to trigger the braking mode, optionally, the brake pedal is provided with a sensor, which can feel the step pressure from the user. When a user depresses the brake pedal 136 of the riding lawn mower 100, the riding lawn mower 100 enters the braking mode, and the walking control module 124 controls the walking motor 123 to brake and decelerate. For example, the walking control module 124 controls the windings 242 of the walking motor 123 to be short-circuited to achieve braking. In another embodiment, the brake pedal 136 is directly coupled with the walking motor 123. Optionally, the brake pedal 136 is coupled with a friction member. When the brake pedal 136 is stepped on, the friction member is brought into contact with the walking motor 123, so that the walking motor 123 decelerates.

[0176] In some embodiments, the brake pedal 136 is coupled with a signal switch. The signal switch is disposed at the bottom of the brake pedal 136. When the brake pedal 136 is depressed to the end, the signal switch provided at the bottom of the brake pedal 136 is triggered to change state, thereby generating a parking signal. Upon receiving the parking signal, the walking control module 124 controls the walking motor 123 to park using the aforementioned parking method. Optionally, after the brake pedal 136 is stepped on to enter the braking mode, when the speed of the walking motor 123 approaches zero, the aforementioned parking mode is triggered, and the riding lawn mower 100 enters the aforementioned parking mode.

[0177] Optionally, the riding lawn mower 100 includes a sensor for detecting the amount of change in the position or angle of the brake pedal 136 before and after being depressed, for example, the pivot angle of rotation of the brake pedal 136, or a sensor for detecting the position of the brake pedal 136 after being depressed. The riding lawn mower 100 further includes a friction plate and a third motor that drives the friction plate. The friction plate is arranged near the walking motor 123, and the friction plate can be driven by the third motor to move to rub against the walking motor to decelerate the walking motor to achieve braking. Optionally, the amount of change in the position or angle before and after the brake pedal 136 is depressed is proportional to the rotational speed or torque of the third motor. The third motor drives the friction plate to move according to the amount of change in the position or angle before and after the brake pedal

136 is depressed, which is detected by the position sensor, to decelerate the walking motor 123.

[0178] In some embodiments, the riding lawn mower 100 includes a power detection module (not shown) for detecting the remaining power of the power supply assembly 14. When the remaining power is detected to be lower than a predefined power threshold, a brake signal is generated, the riding lawn mower 100 enters the braking mode, and the walking control module 124 controls the walking motor 123 to brake and decelerate. Optionally, the walking control module 124 controls the windings 242 of the walking motor 123 to be short-circuited to achieve braking. This braking method uses short-circuit current instead of the power from the power supply assembly to generate braking torque, therefore, it saves electric energy and achieves reliable braking.

[0179] In some embodiments, the riding lawn mower 100 includes a key socket (not shown) for inserting a key to start the riding lawn mower 100. Optionally, when the key is pulled out from the key socket, the walking motor 124 starts to decelerate. For example, the walking control module 124 controls the drive circuit 127 to turn off the electrical connection between the power supply assembly 14 and the walking motor 123 to make the walking motor 123 freely decelerate and stop. Optionally, at this time, the walking control module 124 still maintains a charged state and enters a low power consumption mode.

[0180] In some embodiments, the riding lawn mower 100 includes a seat trigger (not shown). The seat trigger may be a signal switch, a capacitive sensor, a photoelectric switch, etc., arranged near the seat 15 and for sensing whether the user gets up and leaves the seat 15. When the user gets up and leaves the seat 15, the seat trigger can be triggered to change state, thereby triggering the riding lawn mower 100 to enter the braking mode.

[0181] The seat trigger has a first state and a second state. When the seat trigger is in the first state, the seat 15 bears a weight greater than a first predefined weight, and when the seat trigger is in the second state, the seat 15 bears a weight less than a second predefined weight. The first predefined weight is greater than or equal to the second predefined weight. Optionally, the first predefined weight may be a person's weight, and the second predefined weight is one-fifth of the first predefined weight. When the seat 15 bears a weight greater than the first predefined weight, it means that the operator is sitting on the seat 15, and when the seat 15 bears a weight less than the second predefined weight, it means that the operator gets up and leaves the seat 15.

[0182] The walking control module 124 is configured to control the walking motor 123 to brake when the seat trigger changes from the first state to the second state. In other words, when the user gets up and leaves the seat, the walking motor 123 must brake and slow down, so that the riding lawn mower 100 can stop. For example, the walking control module 124 controls the windings of

the walking motor 123 to be short-circuited or controls the drive circuit 127 to control the braking current and braking time.

[0183] Optionally, the walking control module 124 can receive information about the status change of the seat trigger, and the walking control module 124 is configured to: When the seat trigger is changed from the first state to the second state and the time period in the second state is less than a predefined time period, the walking motor 123 is controlled to delay braking. For example, the walking motor 123 can be controlled to delay braking by means of a delay circuit, which can prevent the operator from changing the state of the seat trigger only due to bumps or moving the body, so that the walking control module 124 does not control the walking motor 123 due to undesirable brakes. The predefined weight may also be other weights set by the user. In this way, an operator sitting on the seat can be distinguished from an object placed on the seat.

[0184] In some embodiments, the operating component 13 of the riding lawn mower 100 includes a left operating lever 131L and a right operating lever 132R, and a position sensor (not shown) for sensing the positions of the left operating lever 131L and the right operating lever 132R). Optionally, different braking effects occur when the operating levers 131 are on the inner and outer sides in the left and right direction. For example, when the user sits on the seat 15, and simultaneously pushes the two operating levers 131 outward to the maximum inner position in the left and right direction, the riding lawn mower is triggered to enter the above parking mode, that is, the walking control module 124 controls the walking motor 123 to brake or decelerate freely, and enter the parking mode. When the user moves pushes the operating lever 131 from the forward position or the reverse position to the maximum inner position in the left and right direction, this position is also the middle position of the forward position and the reverse position. At this time, the riding lawn mower 100 enters the braking mode and decelerates. At this time, the walking control module 124 controls the walking motor 123 to brake or decelerate freely, without entering the parking mode.

[0185] In another embodiment, the chassis 16 is configured to carry the seat 15, and the chassis 16 extends at least partially in a direction parallel to the front and rear direction. The seat 15 is used for the operator to sit on, and the seat 15 is mounted on the chassis 16. The seat 15 includes a seat base 151 and a seat back 152. The seat base 151 extends in the front and rear direction, and the seat back 152 extends upward from the base.

[0186] In another embodiment, the operating component 13 may also be implemented as a switch, a handle, and other control devices for the user to operate the riding lawn mower 100. Therefore, the operating component may also include a control panel, which is provided with a plurality of switches, and different switches correspond to different control instructions, and the user inputs different control instructions through the switches to control

the walking motor 123 of the walking assembly 12.

[0187] In another embodiment, the operating component 13 may further include a weight sensor 138 for detecting whether the user is seated, and generating a first signal or a second signal according to the weight of the user when the user is seated. The weight sensor 138 is communicatively connected with the walking control module 124. When the weight sensor 138 senses that the weight is lower than a predefined weight value, the weight sensor 138 sends a second signal to the walking control module 124 to prohibit the riding lawn mower from starting, and the walking control module 124 will prohibit the cutting motor 112 and the walking motor 123 from starting; on the contrary, when the weight sensor 138 senses that the weight reaches the predefined weight value, the weight sensor 138 sends a first signal to the walking control module 124, and the walking control module allows the cutting motor 112 and the walking motor 123 to start. In order to improve the accuracy of detecting whether the user is seated, multiple weight sensors 138 may be provided. For example, a plurality of weight sensors 138 are provided at different locations below the seat base 151, such as the center of the seat base 151 and the position of the seat base 151 near the front side. In other embodiments, the weight sensor 138 may also be provided at the seat back 152, so even if the user adjusts the posture to sit in the rearward position of the seat base 151, it can also be detected by the weight sensor 138. In this way, when the weight sensed by at least one weight sensor 138 reaches the predefined weight value, the walking control module 124 receives the first signal, and the cutting motor 112 and the walking motor 123 are allowed to start.

[0188] In addition, during the operation process of the riding lawn mower 100, the walking control module 124 is configured to control the walking motor 123 to brake when the weight sensor 138 senses that the weight is lower than the predefined weight value. In other words, when the user gets up and leaves the seat, the walking motor 123 must be brake and slow down, so as to stop the riding lawn mower 100. For example, the walking control module 124 controls the windings of the walking motor 123 to be short-circuited or controls the drive circuit 127 to control the braking current and braking time. In some embodiments, during the operation process of the riding lawn mower 100, when the weight sensor 138 senses that the weight is lower than the predefined weight value, the weight sensor 138 sends an automatic parking signal to trigger the automatic parking mode.

[0189] The setting of multiple weight sensors 138 can improve the accuracy of the riding lawn mower 100 in detecting whether the user is seated, and prevent the situation that a user with a small weight is unable to start the riding lawn mower when already seated but not recognized by the weight sensor 138; it can also avoid the situation that the walking control module 124 controls the walking motor 123 to brake due to misrecognition of a weight sensor 138 just because of bumps or moving the

body. At the same time, make sure that the user is seated before starting the riding lawn mower. In this way, the safety of the user is guaranteed and the accuracy of the riding lawn mower in detecting whether the user is seated is also improved.

[0190] The brake assembly 40 is at least used for mechanical braking to prevent the walking wheels from moving relative to the chassis 16. In this embodiment, the brake assembly includes a brake pedal 136 for triggering the riding lawn mower 100 to brake. In an embodiment, the brake pedal 136 is provided with a pressure sensor, which can feel the user's stepping pressure. In another embodiment, the brake pedal 136 is directly coupled with the walking motor 123. Optionally, the brake pedal 136 is coupled with a friction member. When the brake pedal 136 is stepped on, the friction member is brought into contact with the walking wheel, so that the walking wheel decelerates.

[0191] Wherein, the brake assembly 40 also includes a first signal switch. Optionally, the first signal switch is arranged at the bottom of the brake pedal 136. When the brake pedal 136 is stepped on to bring the pedal arm to a predefined position, the brake assembly 40 can be triggered to output a brake signal. When the brake pedal 136 is depressed to the predefined position, the signal switch provided at the bottom of the brake pedal 136 is triggered to change the state, thereby outputting a brake signal, and the second walking wheel brakes to stop quickly. In another embodiment, the brake assembly 40 further includes a limiting member for preventing the brake pedal 136 from moving when the brake pedal 136 is depressed to a predefined position, so that the friction member coupled with the brake pedal 136 maintains the pressure against the walking wheel to prevent the walking wheel from moving relative to the chassis 16. When the brake pedal 136 is stepped on again, the limiting member releases the brake pedal 136 to restore the brake pedal 136 to its original position, so that the friction member is away from the walking wheel, so that the walking wheel can move freely.

[0192] Optionally, the riding lawn mower 100 further includes a power supply circuit 145. The power supply circuit 145 is connected to the power supply assembly 14. The power supply circuit 145 is configured to receive power from the power supply assembly 14 and convert the power of the power supply assembly 14 into the electric energy at least used by the walking control module 124.

[0193] In some embodiments, the riding lawn mower 100 further includes an operation panel 22. The operation panel 22 can display the remaining power of the power supply assembly 14 and the operating status information of the riding lawn mower 100, and is provided with a start button or a start switch for the user to control the start of the smart lawn mower. In some embodiments, the operation panel 22 is connected to the walking control module 124. When the user sends a start command through a button or a switch, the power supply assembly 14 re-

ceives and responds, so that the power supply assembly outputs electric energy to the cutting motor 112, the walking motor 123, and other electronic components of the riding lawn mower 100 to start the riding lawn mower 100. Optionally, the operating status information of the riding lawn mower includes the current mode of the riding lawn mower, such as: automatic parking mode, sleep mode, etc. The operating status information of the riding lawn mower may also include the current fault information of the riding lawn mower, etc. The operation panel 22 and the walking control module 124 are communicationally connected, and such a connection can be implemented in any suitable manner, including but not limited to a wired or wireless connection. The operation panel 22 can also be provided on a mobile terminal such as a mobile phone, and the user can monitor and control the riding lawn mower 100 through the mobile terminal such as a mobile phone, which improves usage convenience.

[0194] In some embodiments, in the embodiment using the weight sensor 133, during the operation process of the riding lawn mower 100, when the user leaves the seat, the weight sensor 133 sends out an automatic parking signal to trigger the automatic parking mode, the walk control module 124 receives the automatic parking signal and controls the walking motor 123 to brake to realize automatic parking.

[0195] In some embodiments, if the walking control module 124 does not receive other control signals after the riding lawn mower 100 enters the automatic parking mode for a period of time, the riding lawn mower enters the sleep mode. For example, the power supply assembly 14 stops supplying power to the cutting motor 112, the walking motor 123, and other electronic components of the riding lawn mower 100, but still provides power to the operation panel 22, so the operation panel 22 can still display the remaining power of the power supply assembly 14. In an embodiment, when the user triggers the start button or start switch of the operation panel 22 of the riding lawn mower 100, the power supply assembly 14 continues to supply power to the cutting motor 112, the walking motor 123, and other electronic components of the riding lawn mower 100, and the riding lawn mower 100 exits the sleep mode. In this way, the riding lawn mower 100 enters the sleep mode when not in use, which can save power and extend the power supply time of the power supply assembly.

[0196] However, the riding lawn mower 100 can stand still on the ramp through the automatic parking mode, if the riding lawn mower automatically enters the sleep mode and exits the automatic parking mode after a period of time, or the riding lawn mower is parked on the ramp for a long time through the automatic parking mode, and the power supply assembly 14 continues to provide power until it is completely discharged or the power is too low, the riding lawn mower 100 will be powered off. In this case, if the brake pedal 136 is not stepped on to the predefined position at this time, the walking wheels can move freely, which may cause the riding lawn mower 100

to slide and bring safety hazards.

[0197] Thus, in some embodiments, the riding lawn mower 100 further includes an alarm assembly 50. The alarm assembly 50 is connected with the walking control module 124 to issue an alarm under predefined conditions to alert the user. In an embodiment, the alarm assembly 50 at least includes a buzzer. When the riding lawn mower 100 enters the automatic parking mode on a ramp and the brake pedal 136 is not stepped on to the predefined position, the walking control module 124 sends a buzzer control command to control the buzzer to send an alarm to remind the user that the riding lawn mower 100 may have sliding hazards. In an embodiment, the walking control module 124 is configured to: after receiving an automatic parking signal, that is, when the riding lawn mower 100 enters the automatic parking mode, if it is determined that the operating parameter of the walking motor is greater than a predefined threshold, control the alarm assembly to issue an alarm. For example, the walking control module determines whether the first current output by the power supply assembly 14 to the walking motor is greater than a predefined current value, and if the first current output by the power supply assembly 14 is greater than the predefined current value, then it is determined that the riding lawn mower 100 is parked on a ramp; check whether the brake pedal 136 is at a predefined position, if the walking control module 124 does not receive a brake signal at this time, then it is determined that the brake pedal 136 is not at the predefined position, thus control the buzzer to issue an alarm. If the first current output by the power supply assembly 14 is less than or equal to the predefined current value, it is determined that the riding lawn mower 100 is parked on a flat ground, and therefore, there is no sliding hazard for the riding lawn mower 100, wherein the first current can be directly detected by the current detection module 29. In another embodiment, the walking control module 124 is configured to: when the riding lawn mower enters the automatic parking mode, determine whether the output torque of the walking motor 123 is greater than a predefined torque threshold; if the output torque of the walking motor 123 is greater than the predefined torque threshold, then it is determined that the riding lawn mower 100 is parked on a ramp; check whether the brake pedal 136 is at a predefined position, if the walking control module 124 does not receive a brake signal at this time, then it is determined that the brake pedal 136 is not at the predefined position, thus control the buzzer to issue an alarm. If the output torque of the walking motor 123 is less than or equal to the predefined torque threshold, it is determined that the riding lawn mower 100 is parked on a flat ground, and therefore, there is no sliding hazard for the riding lawn mower 100.

[0198] The alarm assembly 50 also includes a brake indicator light. When the riding lawn mower 100 enters the automatic parking mode and the brake pedal 136 is not stepped on to the predefined position, the walking control module 124 controls the brake indicator light to

flash to remind the user that the brake is not properly applied, and the riding lawn mower 100 may have sliding hazards. In an embodiment, when the riding lawn mower 100 enters the automatic parking mode and the brake pedal 136 is not stepped on to the predefined position, the walking control module 124 controls the operation panel 22 to display a predefined image to remind the user that the brake is not properly applied, and the riding lawn mower 100 may have sliding hazards.

[0199] In some embodiments, the riding lawn mower 100 includes a key socket (not shown) for inserting a key to start the riding lawn mower 100. For example, after the key is inserted into the key socket, and the user triggers the start button or start switch of the operation panel 22, the power supply assembly 14 provides electric power to the cutting motor 112, the walking motor 123, the walking control module 124, and other power consumption modules to make the riding lawn mower operate normally. Optionally, when the key is pulled out of the key socket for more than a predefined time, the riding lawn mower 100 enters the sleep mode.

[0200] Referring to FIG. 19, a control method of the riding lawn mower 100 includes:

Step S30: the riding lawn mower is in operation;

[0201] The walking control module 16 controls the riding lawn mower 100 to operate normally. In some embodiments, after the key is inserted into the key socket, and the user triggers the start button or start switch of the operation panel 22, the power supply assembly 14 provides electric power to the cutting motor 112, the walking motor 123, and the riding lawn mower 100 of other power consumption modules to make the riding lawn mower operate normally.

[0202] Step S31: determine whether the riding lawn mower needs to enter the automatic parking mode; For example, when automatic parking is needed, the user sends an automatic parking signal by operating the operating component 13 to trigger the riding lawn mower 100 to enter the automatic parking mode. As described above, in the embodiment using the operating lever 131, the user sends an automatic parking signal to trigger the automatic parking mode by pushing the operating lever 131 to the automatic parking position, and the operation sensing module 132 detects that the operating lever 131 is in the automatic parking position, and sends the detected position information to the walking control module 124, and the walking control module 124 controls the walking motor 123 to realize automatic parking. In the embodiment in which two operating levers respectively control two walking motors 123, the user issues an automatic parking command by pushing both operating levers 131 to the automatic parking position. If the operation sensing module 132 detects the automatic parking signal that the riding lawn mower 100 needs to enter the automatic parking mode, then go to step S32. If the operation sensing module 132 does not detect the automatic parking signal that the riding lawn mower 100 needs to enter the automatic parking mode, the riding

lawn mower 100 continues to maintain the operation state.

[0203] Step S32: obtain the rotational speed of the walking motor;

5 When it is determined that the riding lawn mower 100 needs to enter the automatic parking mode, the speed detection module 128 detects the rotational speed of the walking motor and sends it to the walking control module 124, and the walking control module obtains the detected rotational speed of the walking motor 123.

[0204] Step S33: determine whether the rotational speed of the walking motor is less than or equal to a predefined speed threshold.

10 **[0205]** The walking control module 124 compares the rotational speed of the walking motor 123 detected by the speed detection module 128 with a predefined speed threshold to determine whether the rotational speed of the walking motor 123 is less than or equal to the predefined speed threshold. If it is determined that the rotational speed of the walking motor 123 is greater than or equal to the predefined speed threshold, then go to step S32, continue to obtain the rotational speed of the walking motor 123 and determine whether the rotational speed is less than or equal to the predefined speed threshold.

15 **[0206]** Step S34: apply a first torque that is opposite to the tendency of rotation of the walking motor to the walking motor, wherein the first torque is configured to make the riding lawn mower to stand still in one position.

20 **[0207]** After determining that the rotational speed of the walking motor 123 is less than or equal to the predefined speed threshold, apply a first torque that is opposite to the tendency of rotation of the walking motor 123 to the walking motor 123. For example, the walking control module 124 outputs a control signal to the drive circuit 127, and the drive circuit 127 adjusts the magnitude and direction of the first current, so that the walking motor 123 generates the first torque. The first torque has equal magnitude and opposite direction to the external force torque of the riding lawn mower 100 that causes the riding lawn mower 100 to have a tendency to slide. The first torque is configured to make the riding lawn mower to stand still in one position.

[0208] Step S35: determine whether the brake pedal 136 is at the predefined position.

25 **[0209]** The walking control module determines whether the brake pedal 136 is at the predefined position according to the brake signal. If it is determined that the brake pedal 136 is not at the predefined position, then go to step S36; if it is determined that the brake pedal 136 is at the predefined position, then go to step S38 to control the riding lawn mower 100 to enter the sleep mode.

30 **[0210]** Step S36: determine whether the first current output by the power supply assembly to the walking motor is greater than a predefined current value.

35 **[0211]** The walking control module 124 compares the first current output by the power supply assembly detected by the current detection module 29 with the predefined

current value to determine whether the first current value is greater than the predefined current value. If it is determined that the first current is greater than the predefined current value, then go to step S37; if it is determined that the first current is less than or equal to the predefined current value, then go to step S38 to control the riding lawn mower 100 to enter the sleep mode.

[0212] Step S37: the alarm assembly issues an alarm.

[0213] The walking control module 124 sends an alarm signal to the alarm assembly 50 so that the alarm assembly 50 issues an alarm to remind the user. In an embodiment, the alarm assembly 50 includes at least a buzzer. When the riding lawn mower 100 enters the automatic parking mode on a ramp and the brake pedal 136 is not stepped on to the predefined position, the walking control module 124 controls the buzzer to issue an alarm to remind the user that the riding lawn mower 100 may have sliding hazards. In another embodiment, the alarm assembly 50 further includes an indicator light. When the riding lawn mower enters the automatic parking mode and the brake pedal 136 is not stepped on to the predefined position, the walking control module controls the brake indicator light to flash to remind the user that the brake is not properly applied, and the riding lawn mower 100 may have sliding hazards.

[0214] Step S38: the riding lawn mower enters the sleep mode.

[0215] After a predefined period of time, the walking control module 124 controls the riding lawn mower to enter the sleep mode. That is, the walking control module 124 sends a sleep signal to the power supply assembly 14 to stop supplying electric energy to the cutting motor 112, the walking motor 123, and other electronic components of the riding lawn mower 100.

Claims

1. A riding lawn mower (100), comprising:
 - a chassis (16);
 - a power output assembly (11) connected to the chassis and comprising a mowing element (111);
 - a walking assembly (12) comprising a walking wheel (121, 122), a walking motor (123) for driving the walking wheel to travel, and a walking control module (124) for controlling the walking motor; and
 - a first operating component (134) configured to set a plurality of starting modes of the walking motor, the first operating component having:
 - a first operating state configured to start the walking motor in a first starting mode, wherein in the first starting mode, the walking motor starts at a first starting acceleration; and

a second operating state configured to start the walking motor in a second starting mode, wherein in the second starting mode, the walking motor starts at a second starting acceleration; wherein the second starting acceleration is greater than the first starting acceleration; **characterized in that** the power output assembly also comprises a cutting motor (112) for driving the mowing element to move, and a cutting control module (113) for controlling the cutting motor; the first operating component is also configured to set a plurality of braking modes of the walking motor; and the first operating component also has:

- a fourth operating state configured to brake the walking motor in a first braking mode, and in the first braking mode, the walking motor brakes with a first braking acceleration; and
 - a fifth operating state configured to brake the walking motor in a second braking mode, and in the second braking mode, the walking motor brakes with a second braking acceleration; wherein the second braking acceleration is different from the first braking acceleration;
- the riding lawn mower further comprises a second operating component (135) configured to send a brake signal to brake the walking motor; wherein the walking control module is configured to:

- in response to a start signal, start the walking motor according to the starting mode corresponding to the operating state of the first operating component;
- in response to the brake signal, brake the walking motor according to the braking mode corresponding to the operating state of the first operating component; and
- the second operating component (135) is further configured to send a parking signal to trigger the riding lawn mower to enter a parking mode; wherein the walking control module is configured to:
 - in response to the parking signal, determine whether a rotational speed of the walking motor is less than or equal to a predefined speed threshold; after determining that

- the rotational speed of the walking motor is less than or equal to the predefined speed threshold, apply a first torque opposite to a tendency of rotation of the walking motor to the walking motor, and the first torque is configured to enable the riding lawn mower to stand still in a position.
2. The riding lawn mower of claim 1, wherein the first operating component further has:
- a third operating state configured to start the walking motor in a third starting mode, and in the third starting mode, the walking motor starts at a third starting acceleration; wherein the third starting acceleration is greater than the second starting acceleration.
3. The riding lawn mower of claim 1, further comprising:
- a power supply assembly (14) configured to provide electric energy for the walking motor; when the power supply assembly supplies a first amount of power, either the walking motor starts at the first starting acceleration in the first starting mode, or the walking motor starts at the second starting acceleration in the second starting mode; when the power supply assembly supplies a second amount of power, either the walking motor starts at a third starting acceleration in the first starting mode, or the walking motor starts at a fourth starting acceleration in the second starting mode; wherein the first starting acceleration is different from the third starting acceleration, and the second starting acceleration is different from the fourth starting acceleration.
4. The riding lawn mower of claim 1, wherein:
- the second operating component is configured to send a start signal to start the walking motor; and the walking control module is configured to: in response to the start signal, start the walking motor according to the starting mode corresponding to the operating state of the first operating component.
5. The riding lawn mower of claim 1, wherein the first torque and a torque of an external force of the riding lawn mower that causes the riding lawn mower to have a tendency to slide are of a same magnitude and opposite directions.
6. The riding lawn mower of claim 1, wherein the walking control module is configured to: in response to the rotational speed of the walking motor being less than or equal to the predefined speed threshold, control a power supply assembly to output a first current to the walking motor, and the first current enables the walking motor to generate the first torque.
7. The riding lawn mower of claim 6, wherein the walking motor comprises a rotor, the riding lawn mower further comprises a rotor position detection module configured to detect a position of the rotor of the walking motor, and the walking control module is configured to:
- in response to the rotational speed of the walking motor being less than or equal to the predefined speed threshold, select a current position of the rotor of the walking motor as a reference position; in response to a state in which the rotor deviates from the reference position, control the power supply assembly to output the first current to the walking motor so that the walking motor generates the first torque, and the first torque makes the rotor of the walking motor return to the reference position.
8. The riding lawn mower of claim 1, wherein the second operating component is further configured to send an acceleration signal to trigger the riding lawn mower to exit the parking mode, and the walking control module is configured to:
- in response to the acceleration signal, determine whether a direction of a second torque to be generated by the walking motor corresponding to the acceleration signal is the same as a direction of the first torque; if the direction of the second torque is the same as the direction of the first torque, then determine whether the second torque is greater than or equal to the first torque; if it is determined that the second torque is greater than or equal to the first torque, control the riding lawn mower to exit the parking mode; if the direction of the second torque is opposite to the direction of the first torque, control the riding lawn mower to exit the parking mode.
9. The riding lawn mower of claim 8, wherein the second operating component is further configured to set a target speed and direction of the walking motor, and the walking control module is configured to: in response to an end of the parking mode, control the walking motor to run at the target speed and direction according to the target speed and direction

set by the second operating component.

10. The riding lawn mower of claim 1, further comprising:

a detection device (29) for detecting an operating parameter of the walking motor when the riding lawn mower is in the parking mode; a brake assembly (40) for at least mechanical braking to prevent the walking wheel from moving relative to the chassis, wherein the brake assembly outputs the brake signal when triggered by a user; and an alarm assembly (50) configured to issue an alarm to remind the user; wherein the walking control module is configured to:

receive the parking signal to make the riding lawn mower in the parking mode; when the riding lawn mower is in the parking mode and the brake signal is not received, determine whether the operating parameter of the walking motor is greater than a predefined threshold value; if the operating parameter of the walking motor is greater than the predefined threshold value, control the alarm assembly to issue an alarm.

11. The riding lawn mower of claim 10, wherein the walking control module is configured to:

in response to the alarm assembly issuing an alarm, determine whether the brake signal is received; and in response to the received brake signal, control the alarm assembly to dismiss the alarm.

12. The riding lawn mower of claim 10, wherein the walking control module is configured to:

determine whether the riding lawn mower is in the parking mode for a time greater than or equal to a predefined period of time; in response to the riding lawn mower being in the parking mode for a time greater than or equal to the predefined period of time, and the brake signal is received, control the riding lawn mower to enter a sleep mode.

Patentansprüche

1. Aufsitzrasenmäher (100), umfassend:

ein Fahrgestell (16); eine mit dem Fahrgestell verbundene Leistungsabgabebaupruppe (11), die ein Mähеле-

ment (111) umfasst; eine Laufeinheit (12), die ein Laufrad (121, 122), einen Laufmotor (123) zum Antreiben des Laufrads zum Laufen und ein Laufsteuermodul (124) zum Steuern des Laufmotors umfasst; und eine erste Bedienungskomponente (134), die so ausgelegt ist, dass sie eine Vielzahl von Startmodi des Laufmotors einstellt, wobei die erste Bedienungskomponente Folgendes aufweist:

einen ersten Betriebszustand, der so ausgelegt ist, dass der Laufmotor in einem ersten Startmodus gestartet wird, wobei im ersten Startmodus der Laufmotor mit einer ersten Startbeschleunigung startet; und einen zweiten Betriebszustand, der so ausgelegt ist, dass der Laufmotor in einem zweiten Startmodus gestartet wird, wobei der Laufmotor im zweiten Startmodus mit einer zweiten Startbeschleunigung startet; wobei die zweite Startbeschleunigung größer als die erste Startbeschleunigung ist; **dadurch gekennzeichnet, dass** die Leistungsabgabebaupruppe auch einen Mähmotor (112) für den Antrieb der Bewegung des Mähelementes und ein Mähsteuermodul (113) zur Steuerung des Mähmotors umfasst; die erste Bedienungskomponente ist außerdem so ausgelegt, dass sie eine Vielzahl von Bremsmodi des Laufmotors einstellt; und die erste Bedienungskomponente hat außerdem:

einen vierten Betriebszustand, der so ausgelegt ist, dass der Laufmotor in einem ersten Bremsmodus gebremst wird, und im ersten Bremsmodus bremst der Laufmotor mit einer ersten Bremsbeschleunigung; und einen fünften Betriebszustand, der so ausgelegt ist, dass der Laufmotor in einem zweiten Bremsmodus gebremst wird, und im zweiten Bremsmodus bremst der Laufmotor mit einer zweiten Bremsbeschleunigung; wobei die zweite Bremsbeschleunigung sich von der ersten Bremsbeschleunigung unterscheidet; der Aufsitzrasenmäher umfasst ferner eine zweite Bedienungskomponente (135), die so ausgelegt ist, dass sie ein Bremssignal zum Abbremsen des Laufmotors sendet; wobei das Laufkontrollmodul so ausgelegt ist, dass es:

als Reaktion auf ein Startsignal

den Laufmotor gemäß dem Startmodus startet, der dem Betriebszustand der ersten Bedienungskomponente entspricht;
als Reaktion auf das Bremssignal den Laufmotor entsprechend dem Bremsmodus abbremst, der dem Betriebszustand der ersten Bedienungskomponente entspricht; und die zweite Bedienungskomponente (135) ist ferner so ausgelegt, dass sie ein Parksignal sendet, um den Aufsitzrasenmäher in einen Parkmodus zu versetzen; wobei das Laufkontrollmodul so ausgelegt ist, dass es:
als Reaktion auf das Parksignal bestimmt, ob eine Drehgeschwindigkeit des Laufmotors kleiner oder gleich einem vordefinierten Drehzahlschwellenwert ist; nach der Bestimmung, dass die Drehzahl des Laufmotors kleiner oder gleich der vordefinierten Drehzahlschwelle ist, Anwendung eines ersten Drehmomentes auf den Laufmotor, das der Rotationstendenz des Laufmotors entgegengesetzt ist; und das erste Drehmoment so ausgelegt ist, dass der Aufsitzrasenmäher in einer Position stillstehen kann.

2. Aufsitzrasenmäher nach Anspruch 1, wobei die erste Bedienungskomponente ferner Folgendes aufweist:

einen dritten Betriebszustand, der so ausgelegt ist, dass der Laufmotor in einem dritten Startmodus gestartet wird, und im dritten Startmodus startet der Laufmotor mit einer dritten Startbeschleunigung;
wobei die dritte Startbeschleunigung größer als die zweite Startbeschleunigung ist.

3. Aufsitzrasenmäher nach Anspruch 1, ferner umfassend:

eine Stromversorgungseinheit (14), die so ausgelegt ist, dass sie elektrische Energie für den Laufmotor bereitstellt;
wenn die Stromversorgungsbaugruppe eine erste Energiemenge liefert, startet entweder der Laufmotor mit der ersten Startbeschleunigung im ersten Startmodus; oder der Laufmotor startet mit der zweiten Startbeschleunigung im zweiten Startmodus;
wenn die Stromversorgungsbaugruppe eine

zweite Energiemenge liefert, startet der Laufmotor entweder mit einer dritten Startbeschleunigung im ersten Startmodus oder der Laufmotor startet mit einer vierten Startbeschleunigung im zweiten Startmodus;
wobei die erste Startbeschleunigung sich von der dritten Startbeschleunigung unterscheidet und die zweite Startbeschleunigung sich von der vierten Startbeschleunigung unterscheidet.

4. Aufsitzrasenmäher nach Anspruch 1, wobei:

die zweite Bedienungskomponente so ausgelegt ist, dass sie ein Startsignal zum Starten des Laufmotors sendet; und
das Modul zur Laufsteuerung ist so ausgelegt, dass es:
als Reaktion auf das Startsignal den Laufmotor entsprechend dem Startmodus startet, der dem Betriebszustand der ersten Bedienungskomponente entspricht.

5. Aufsitzrasenmäher nach Anspruch 1, wobei das erste Drehmoment und ein Drehmoment einer äußeren Kraft des Aufsitzrasenmähers, die den Aufsitzrasenmäher zum Rutschen veranlasst, gleich groß sind und in entgegengesetzte Richtungen wirken.

6. Aufsitzrasenmäher nach Anspruch 1, wobei das Laufkontrollmodul so konfiguriert ist, dass es:
als Reaktion darauf, dass die Drehzahl des Laufmotors kleiner oder gleich dem vordefinierten Drehzahlschwellenwert ist, eine Stromversorgungsbaugruppe so steuert, dass sie einen ersten Strom an den Laufmotor abgibt und der erste Strom den Laufmotor in die Lage versetzt, das erste Drehmoment zu erzeugen.

7. Aufsitzrasenmäher nach Anspruch 6, wobei der Laufmotor einen Rotor umfasst, der Aufsitzrasenmäher ferner ein Rotorpositionserfassungsmodul umfasst, das dafür ausgelegt ist, eine Position des Rotors des Laufmotors zu erfassen, und das Laufsteuermodul dafür konfiguriert ist:

als Reaktion darauf, dass die Drehzahl des Laufmotors kleiner oder gleich dem vordefinierten Drehzahlschwellenwert ist, eine aktuelle Position des Rotors des Laufmotors als Referenzposition auszuwählen;
als Reaktion auf einen Zustand, in dem der Rotor von der Referenzposition abweicht, die Stromversorgungsanordnung so zu steuern, dass sie den ersten Strom an den Laufmotor abgibt, sodass der Laufmotor das erste Drehmoment erzeugt, und das erste Drehmoment den Rotor des Laufmotors in die Referenzposition zurückkehren lässt.

8. Aufsitzrasenmäher nach Anspruch 1, wobei die zweite Betriebskomponente ferner so ausgelegt ist, dass sie ein Beschleunigungssignal sendet, um den Aufsitzrasenmäher zum Verlassen des Parkmodus zu veranlassen, und das Laufkontrollmodul so ausgelegt ist, dass es:

als Reaktion auf das Beschleunigungssignal bestimmt, ob eine Richtung eines zweiten Drehmoments, das von dem Laufmotor entsprechend dem Beschleunigungssignal erzeugt werden soll, dieselbe ist wie eine Richtung des ersten Drehmomentes;

wenn die Richtung des zweiten Drehmomentes die gleiche ist wie die Richtung des ersten Drehmomentes, dann bestimmt, ob das zweite Drehmoment größer oder gleich dem ersten Drehmoment ist;

wenn festgestellt wird, dass das zweite Drehmoment größer oder gleich dem ersten Drehmoment ist, den Aufsitzrasenmäher so steuert, dass er den Parkmodus verlässt;

wenn die Richtung des zweiten Drehmomentes der Richtung des ersten Drehmomentes entgegengesetzt ist, den Aufsitzrasenmäher so steuert, dass er den Parkmodus verlässt.

9. Aufsitzrasenmäher nach Anspruch 8, wobei die zweite Bedienungskomponente ferner so ausgelegt ist, dass sie eine Sollzahl und eine Richtung des Laufmotors einstellt, und das Laufkontrollmodul ist dafür ausgelegt, als Reaktion auf ein Ende des Parkmodus den Laufmotor so zu steuern, dass er mit der Zieldrehzahl und -richtung entsprechend der von der zweiten Bedienungskomponente eingestellten Zieldrehzahl und -richtung läuft.

10. Aufsitzrasenmäher nach Anspruch 1, ferner umfassend:

eine Detektionsvorrichtung (29) zum Feststellen eines Betriebsparameters des Laufmotors, wenn der Aufsitzrasenmäher im Parkmodus ist; eine Bremsanordnung (40) zum zumindest mechanischen Bremsen, um zu verhindern, dass sich das Laufrad relativ zum Fahrgestell bewegt, wobei die Bremsanordnung das Bremssignal ausgibt, wenn es von einem Benutzer ausgelöst wird; und

eine Alarmeinheit (50), die so ausgelegt ist, dass sie einen Alarm ausgibt, um den Benutzer zu erinnern;

wobei das Laufkontrollmodul so ausgelegt ist, dass es:

das Parksinal empfängt, um den Aufsitzrasenmäher in den Parkmodus zu verset-

zen;

wenn sich der Aufsitzrasenmäher im Parkmodus befindet und das Bremssignal nicht empfangen wird, feststellt, ob der Betriebsparameter des Laufmotors größer als ein vordefinierter Schwellenwert ist; wenn der Betriebsparameter des Laufmotors größer als der vordefinierte Schwellenwert ist, die Alarmeinheit so steuert, dass ein Alarm ausgegeben wird.

11. Aufsitzrasenmäher nach Anspruch 10, wobei das Laufkontrollmodul so konfiguriert ist, dass es:

als Reaktion darauf, dass die Alarmeinheit einen Alarm ausgibt, feststellt, ob das Bremssignal empfangen wird; und

als Reaktion auf das empfangene Bremssignal die Alarmanlage so steuert, dass der Alarm aufgehoben wird.

12. Aufsitzrasenmäher nach Anspruch 10, wobei das Laufkontrollmodul so ausgelegt ist, dass es:

feststellt, ob sich der Aufsitzrasenmäher während einer Zeitspanne, die größer oder gleich einer vordefinierten Zeitspanne ist, im Parkmodus befindet;

als Reaktion darauf, dass sich der Aufsitzrasenmäher für eine Zeitspanne, die größer oder gleich der vordefinierten Zeitspanne ist, im Parkmodus befindet und das Bremssignal empfangen wird, den Aufsitzrasenmäher so steuert, dass er in einen Schlafmodus übergeht.

Revendications

1. Tondeuse à gazon autoportée (100), comprenant :

un châssis (16) ;

un ensemble de sortie électrique (11) connecté au châssis et comprenant un élément de tonte (111) ;

un ensemble de conduite (12) comprenant une roue de conduite (121, 122), un moteur de conduite (123) pour entraîner la roue de conduite en déplacement, et un module de commande de conduite (124) pour commander le moteur de conduite ; et

un premier composant opérationnel (134) configuré pour définir une pluralité de modes de démarrage du moteur de conduite, le premier composant opérationnel ayant :

un premier état opérationnel configuré pour démarrer le moteur de conduite dans un premier mode de démarrage, dans laquelle

dans le premier mode de démarrage, le moteur de conduite démarre à une première accélération de démarrage ; et un deuxième état opérationnel configuré pour démarrer le moteur de conduite dans un deuxième mode de démarrage, dans laquelle dans le deuxième mode de démarrage, le moteur de conduite démarre à une deuxième accélération de démarrage ; dans laquelle la deuxième accélération de démarrage est plus grande que la première accélération de démarrage ;

caractérisée en ce que

l'ensemble de sortie électrique comprend également un moteur de coupe (112) pour entraîner l'élément de tonte en déplacement, et un module de commande de coupe (113) pour commander le moteur de coupe ; le premier composant opérationnel est également configuré pour régler une pluralité de modes de freinage du moteur de conduite ; et le premier composant opérationnel a également :

un quatrième état opérationnel configuré pour freiner le moteur de conduite dans un premier mode de freinage, et dans le premier mode de freinage, le moteur de conduite freine avec une première accélération de freinage ; et un cinquième état opérationnel pour freiner le moteur de conduite dans un deuxième mode de freinage, et dans le deuxième mode de freinage, le moteur de conduite freine avec une deuxième accélération de freinage ; dans laquelle la deuxième accélération de freinage est différente de la première accélération de freinage ; la tondeuse à gazon autoportée comprend en outre un deuxième composant opérationnel (135) configuré pour envoyer un signal de freinage pour freiner le moteur de conduite ; dans laquelle le module de commande de conduite est configuré pour :

en réponse à un signal de démarrage, démarrer le moteur de conduite selon le mode de démarrage correspondant à l'état opérationnel du premier composant opérationnel ; en réponse au signal de freinage, freiner le moteur de conduite selon le mode de freinage correspondant à l'état opérationnel du premier composant opérationnel ; et

le deuxième composant opérationnel (135) est en outre configuré pour envoyer un signal de stationnement pour faire entrer la tondeuse à gazon autoportée dans un mode de stationnement ; dans laquelle le module de commande de conduite est configuré pour :

en réponse au signal de stationnement, déterminer si une vitesse de rotation du moteur de conduite est inférieure ou égale à un seuil de vitesse prédéfini ; après détermination que la vitesse de rotation du moteur de conduite est inférieure ou égale au seuil de vitesse prédéfini, appliquer un premier couple opposé à une tendance de rotation du moteur de conduite sur le moteur de conduite, et le premier couple est configuré pour permettre à la tondeuse à gazon autoportée de rester immobile dans une position.

2. Tondeuse à gazon autoportée selon la revendication 1, dans laquelle le premier composant opérationnel comprend en outre :

un troisième état opérationnel configuré pour démarrer le moteur de conduite dans un troisième mode de démarrage, et dans le troisième mode de démarrage, le moteur de conduite démarre à une troisième accélération de démarrage ;

dans laquelle la troisième accélération de démarrage est plus élevée que la deuxième accélération de démarrage.

3. Tondeuse à gazon autoportée selon la revendication 1, comprenant en outre :

un ensemble d'alimentation électrique (14) configuré pour fournir de l'énergie électrique pour le moteur de conduite ;

lorsque l'ensemble d'alimentation électrique fournit une première quantité de courant, soit le moteur de conduite démarre à la première accélération de démarrage dans le premier mode de démarrage, soit le moteur de conduite démarre à la deuxième accélération de démarrage dans le deuxième mode de démarrage ; lorsque l'ensemble d'alimentation électrique fournit une deuxième quantité de courant, soit le moteur de conduite démarre à une troisième accélération de démarrage dans le premier mode de démarrage, soit le moteur de conduite démarre à une quatrième accélération de démarrage dans le deuxième mode de démarrage ;

- dans lequel la première accélération de démarrage est différente de la troisième accélération de démarrage, et la deuxième accélération de démarrage est différente de la quatrième accélération de démarrage.
4. Tondeuse à gazon autoportée selon la revendication 1, dans laquelle :
- le deuxième composant opérationnel est configuré pour envoyer un signal de départ pour démarrer le moteur de conduite ; et le module de commande de conduite est configuré pour :
- en réponse au signal de départ, démarrer le moteur de conduite selon le mode de démarrage correspondant à l'état opérationnel du premier composant opérationnel.
5. Tondeuse à gazon autoportée selon la revendication 1, dans laquelle le premier couple et un couple d'une force externe de la tondeuse à gazon autoportée qui fait que la tondeuse à gazon autoportée a tendance à glisser sont d'une même grandeur et de directions opposées.
6. Tondeuse à gazon autoportée selon la revendication 1, dans laquelle le module de commande de conduite est configuré pour :
- en réponse à la vitesse de rotation du moteur de conduite étant inférieure ou égale au seuil de vitesse prédéfini, commander un ensemble d'alimentation électrique pour émettre un premier courant vers le moteur de conduite, et le premier courant permet au moteur de conduite de générer le premier couple.
7. Tondeuse à gazon autoportée selon la revendication 6, dans laquelle le moteur de conduite comprend un rotor, la tondeuse à gazon autoportée comprend en outre un module de détection de position de rotor configuré pour détecter une position du rotor du moteur de conduite, et le module de commande de conduite est configuré pour :
- en réponse à la vitesse de rotation du moteur de conduite étant inférieure ou égale au seuil de vitesse prédéfini, sélectionner une position actuelle du rotor du moteur de conduite en tant qu'une position de référence ;
- en réponse à un état dans lequel le rotor dévie de la position de référence, commander l'ensemble d'alimentation électrique à émettre le premier courant vers le moteur de conduite de façon à ce que le moteur de conduite génère le premier couple, et le premier couple fait que le rotor du moteur de conduite retourne à la position de référence.
8. Tondeuse à gazon autoportée selon la revendication 1, dans laquelle le deuxième composant opérationnel est en outre configuré pour envoyer un signal d'accélération pour faire que la tondeuse à gazon autoportée quitte le mode de stationnement, et le module de commande de conduite est configuré pour :
- en réponse au signal d'accélération, déterminer si une direction d'un deuxième couple à générer par le moteur de conduite correspondant au signal d'accélération est la même qu'une direction du premier couple ;
- si la direction du deuxième couple est la même que la direction du premier couple, déterminer alors si le deuxième couple est supérieur ou égal au premier couple ;
- s'il est déterminé que le second couple est supérieur ou égal au premier couple, commander la tondeuse à gazon autoportée à quitter le mode de stationnement ;
- si la direction du deuxième couple est opposée à la direction du premier couple, commander la tondeuse autoportée à quitter le mode de stationnement.
9. Tondeuse à gazon autoportée selon la revendication 8, dans laquelle le deuxième composant opérationnel est en outre configuré pour régler une vitesse et une direction cibles du moteur de conduite, et le module de commande de conduite est configuré pour :
- en réponse à une fin du mode de stationnement, commander le moteur de conduite à fonctionner à la vitesse et à la direction cibles selon la vitesse et la direction cibles réglées par le deuxième composant opérationnel.
10. Tondeuse à gazon autoportée selon la revendication 1, comprenant en outre :
- un dispositif de détection (29) pour détecter un paramètre opérationnel du moteur de conduite lorsque la tondeuse à gazon autoportée est dans le mode de stationnement ;
- un ensemble de frein (40) pour au moins le freinage mécanique pour empêcher la roue de conduite de se déplacer par rapport au châssis, dans lequel l'ensemble de frein émet le signal de freinage lorsqu'il est déclenché par un utilisateur ; et
- un ensemble d'alarme (50) configuré pour émettre une alarme pour un rappel à l'utilisateur ;
- dans laquelle le module de commande de conduite est configuré pour :
- recevoir le signal de stationnement pour mettre la tondeuse à gazon autoportée dans le mode de stationnement ;

- lorsque la tondeuse à gazon autoportée est dans le mode de stationnement et que le signal de freinage n'est pas reçu, déterminer si le paramètre opérationnel du moteur de conduite est supérieur à une valeur seuil prédéfinie ; 5
- si le paramètre opérationnel du moteur de conduite est supérieur à la valeur seuil prédéfinie, commander l'ensemble d'alarme à émettre une alarme. 10
- 11.** Tondeuse à gazon autoportée selon la revendication 10, dans laquelle le module de commande de conduite est configuré pour : 15
- en réponse à l'ensemble d'alarme émettant une alarme, déterminer si le signal de freinage est reçu ; et
- en réponse au signal de freinage reçu, commander l'ensemble d'alarme à arrêter l'alarme. 20
- 12.** Tondeuse à gazon autoportée selon la revendication 10, dans laquelle le module de commande de conduite est configuré pour : 25
- déterminer si la tondeuse à gazon autoportée est dans le mode de stationnement pendant une durée supérieure ou égale à une période de temps prédéfinie ;
- en réponse à la tondeuse à gazon autoportée étant en mode de stationnement pendant une durée supérieure ou égale à une période de temps prédéfinie, et signal de freinage reçu, commander la tondeuse à gazon autoportée à entrer en mode veille. 30 35
- 40
- 45
- 50
- 55

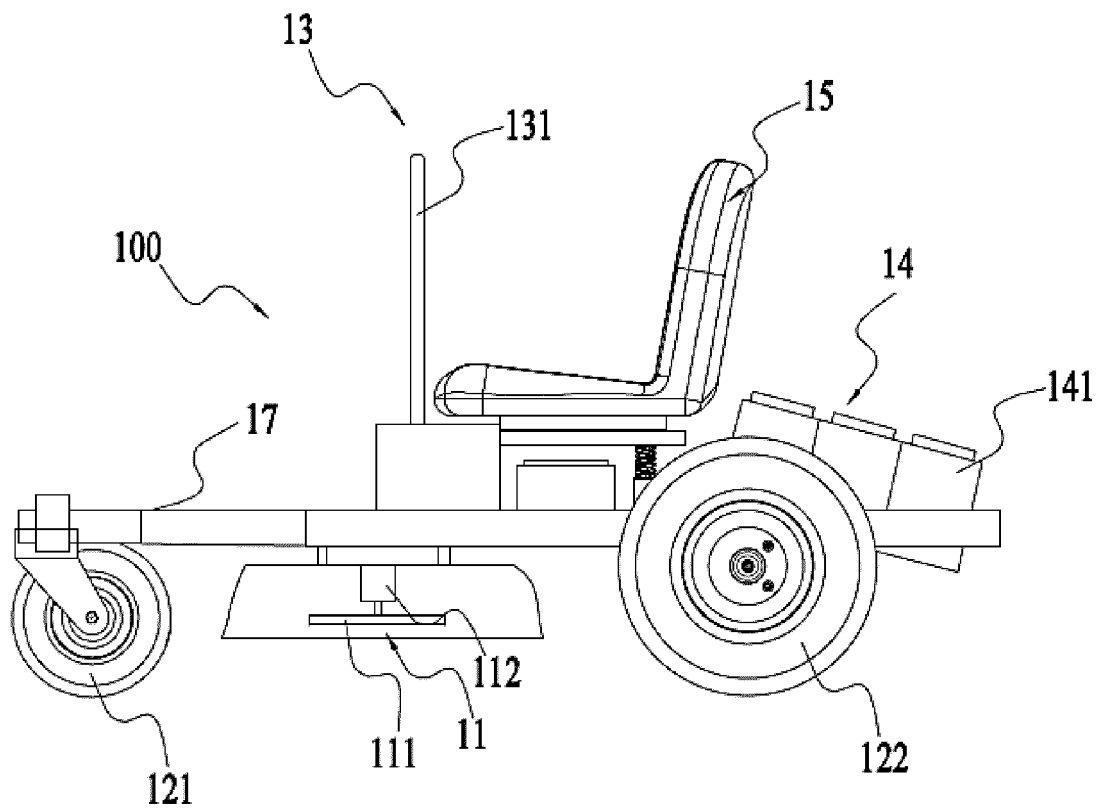


FIG. 1

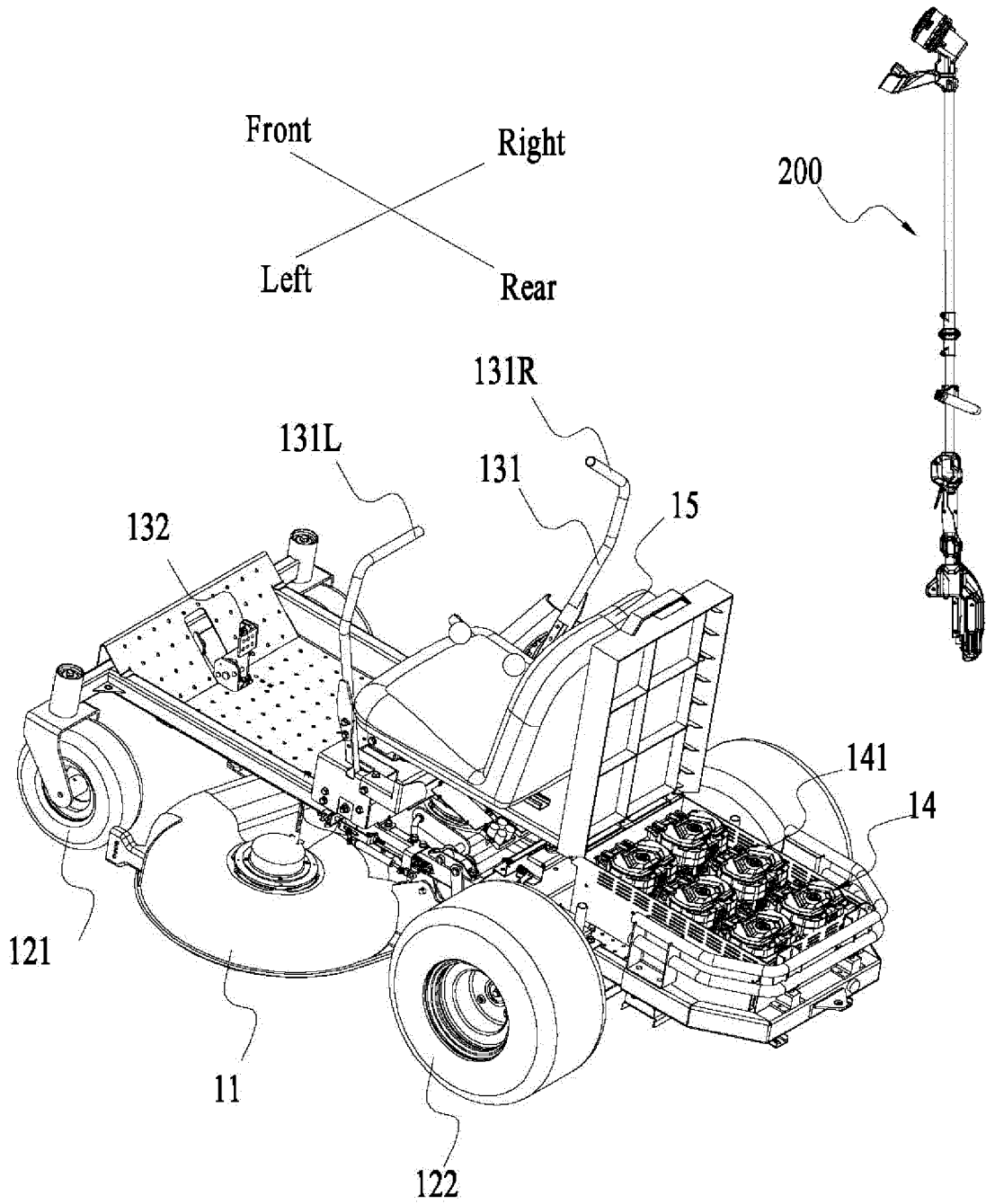


FIG. 2

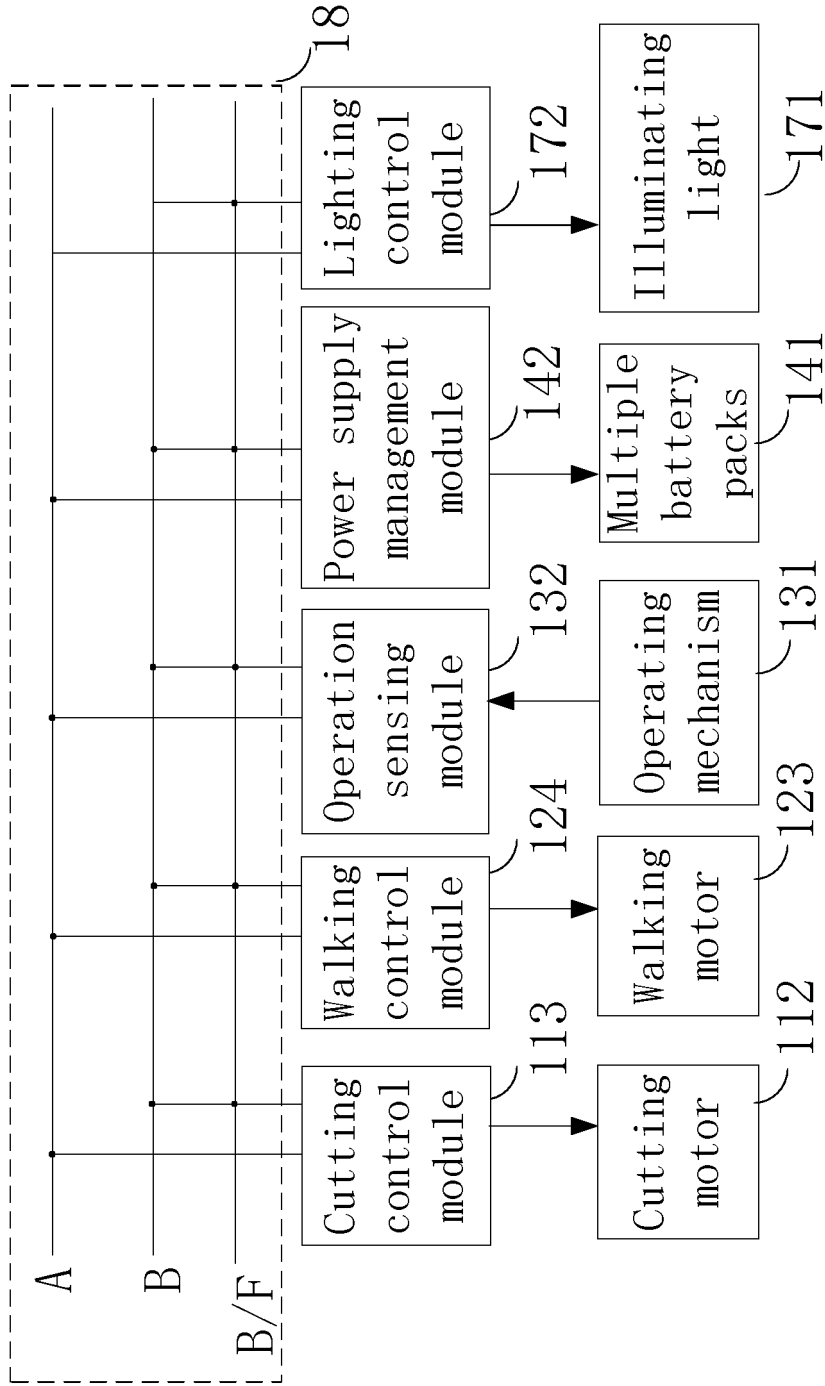


FIG. 3a

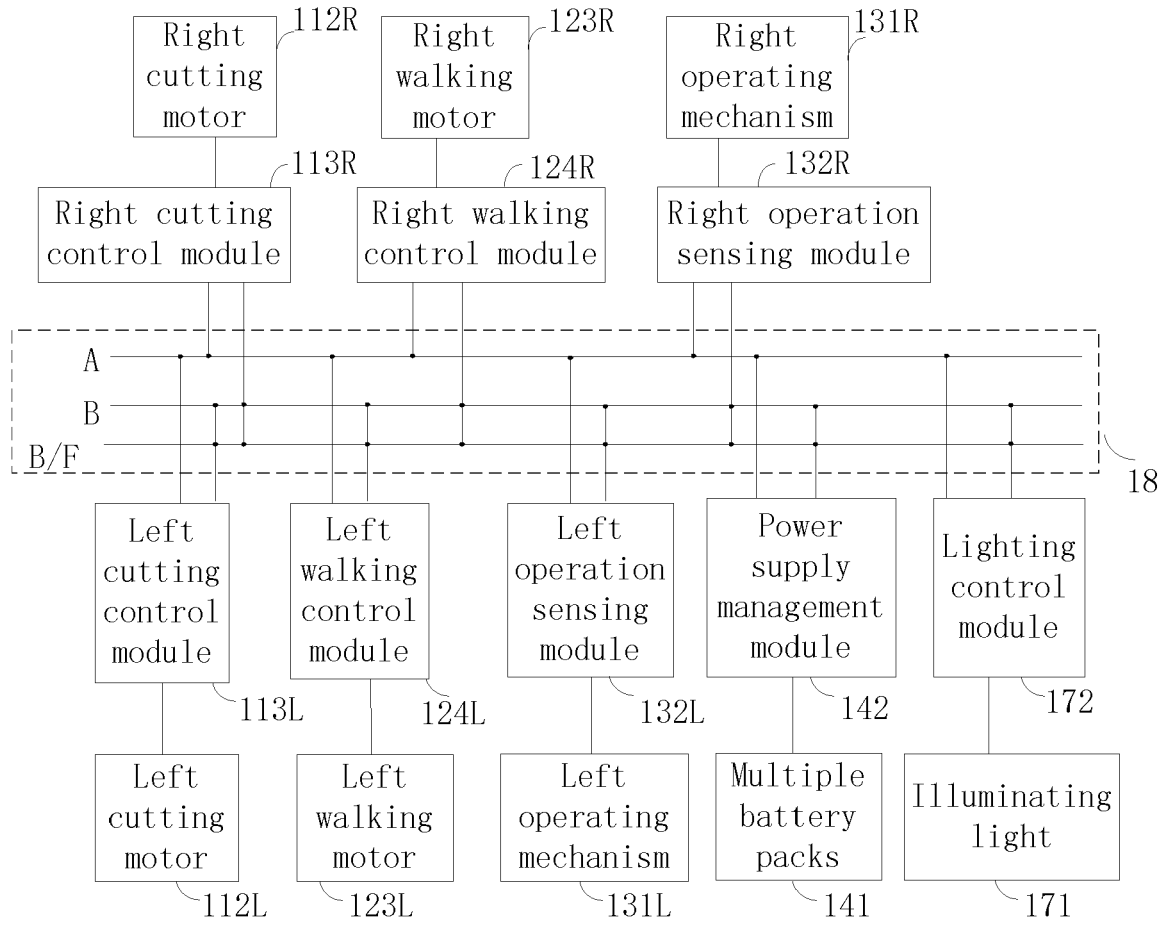


FIG. 3b

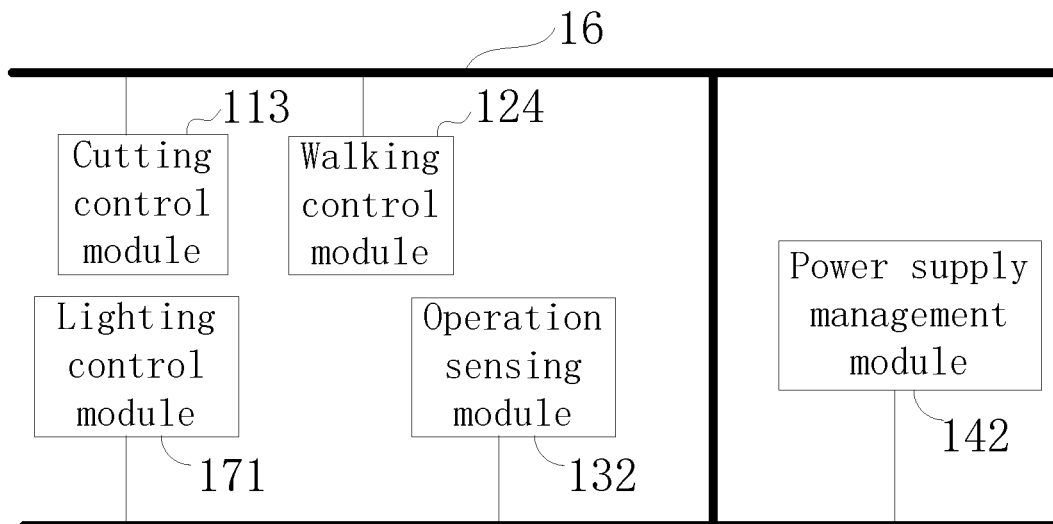


FIG. 4

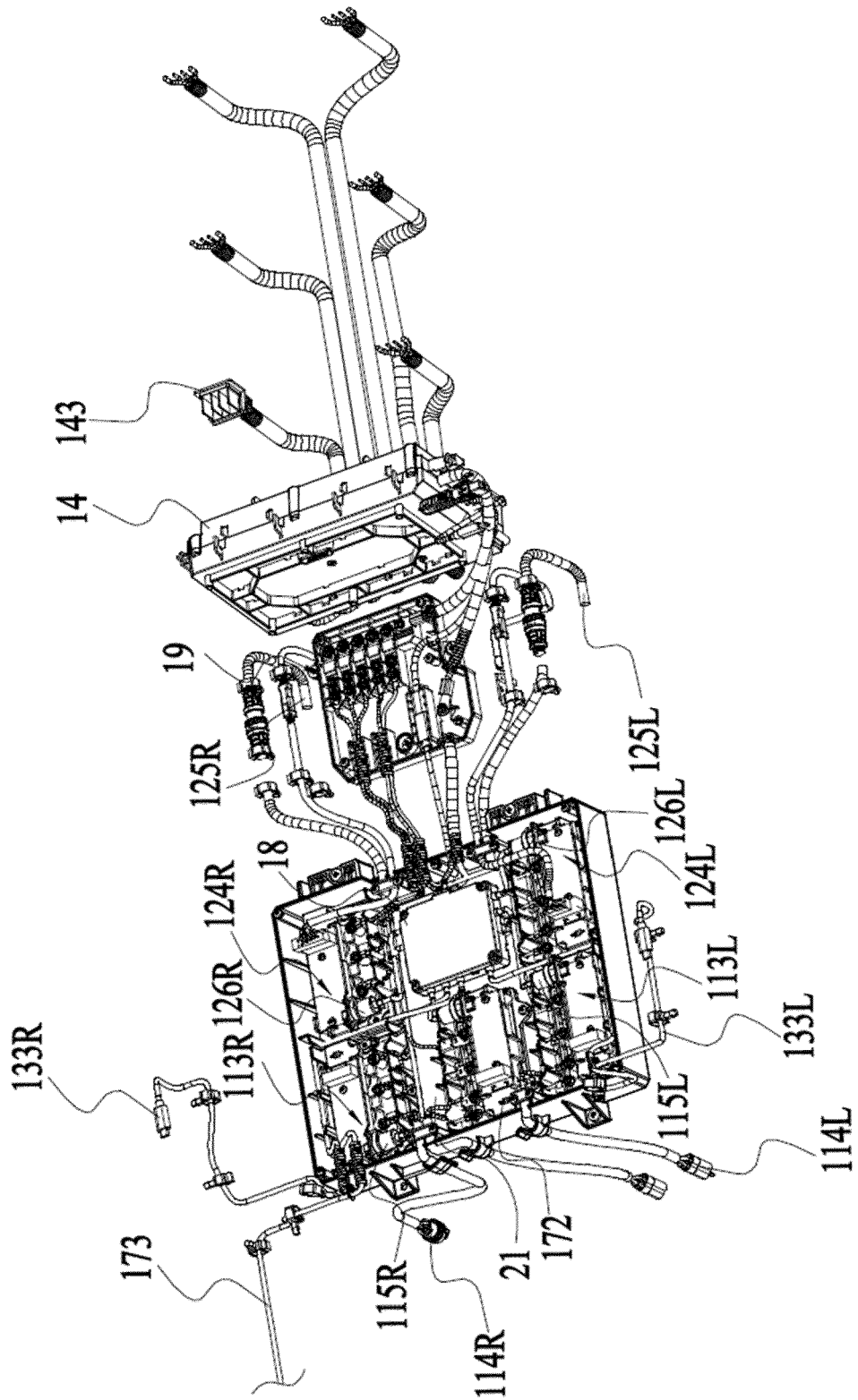


FIG. 5

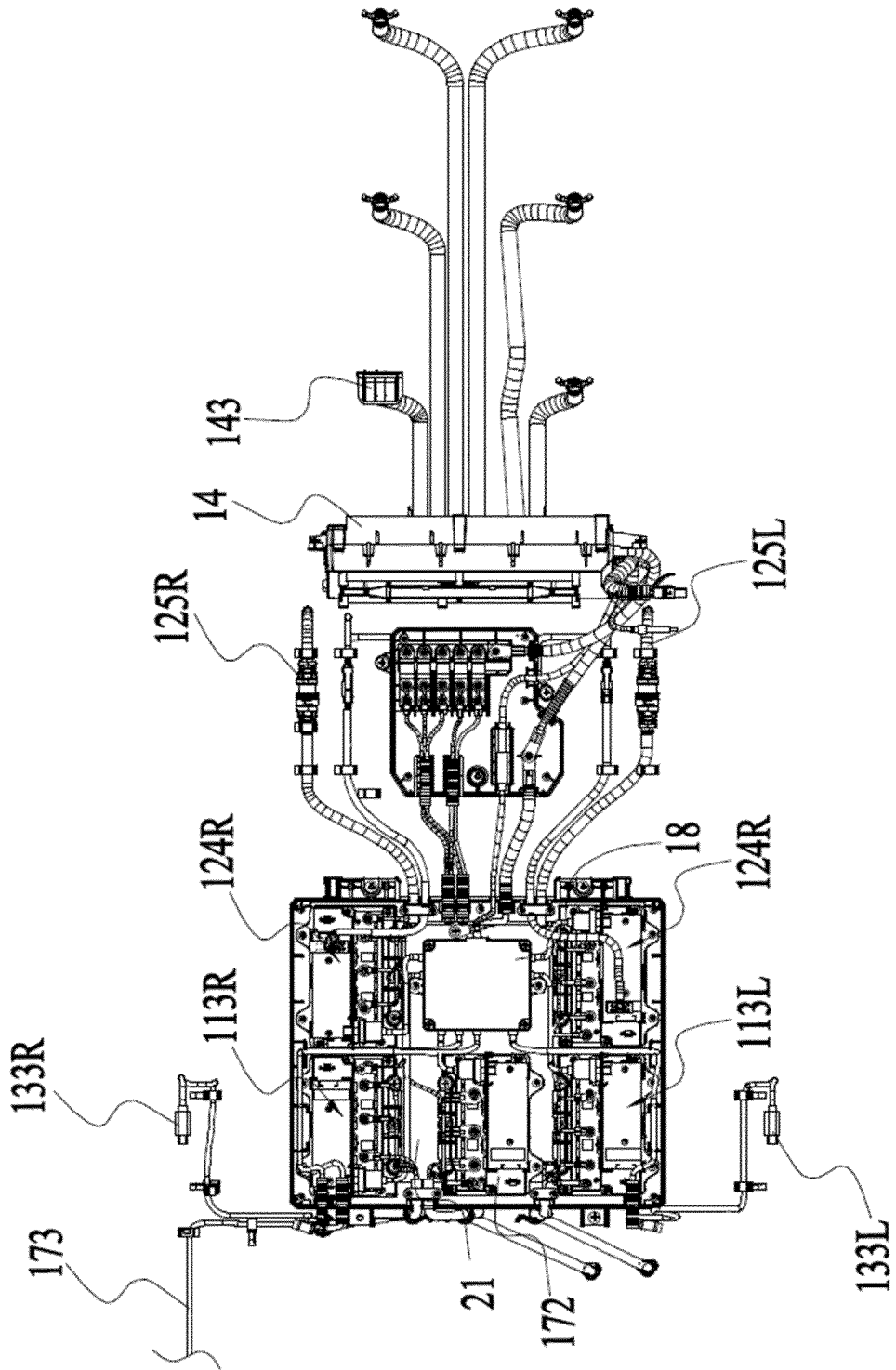


FIG. 6

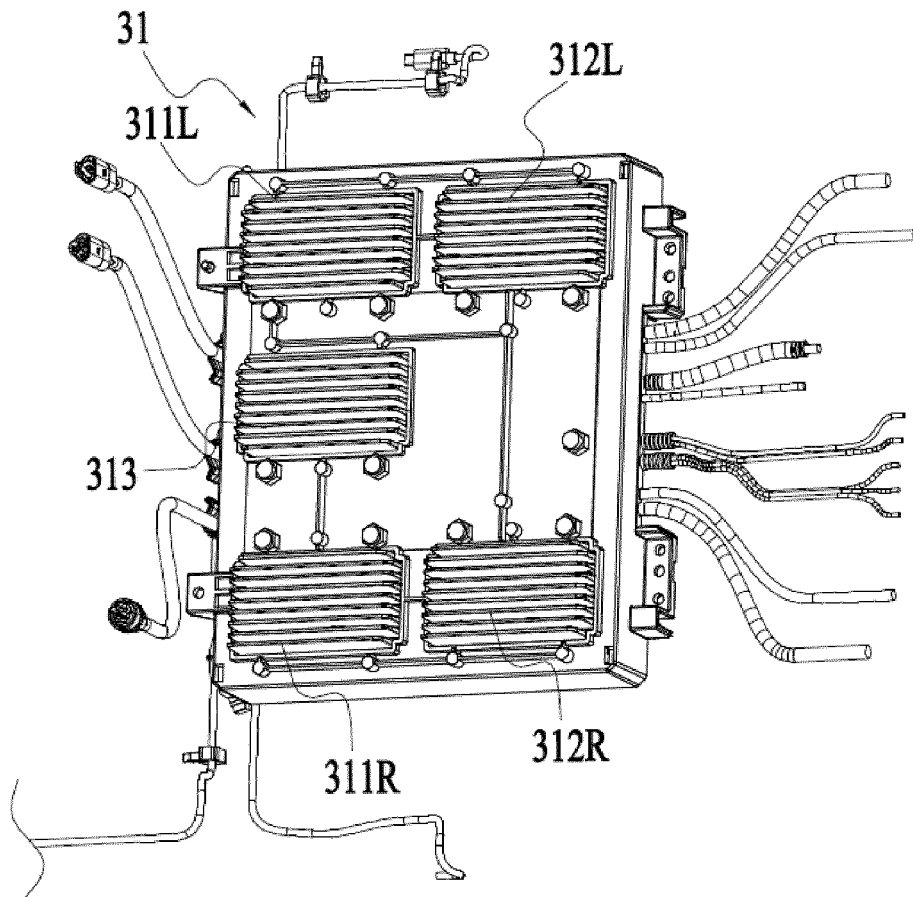


FIG. 7

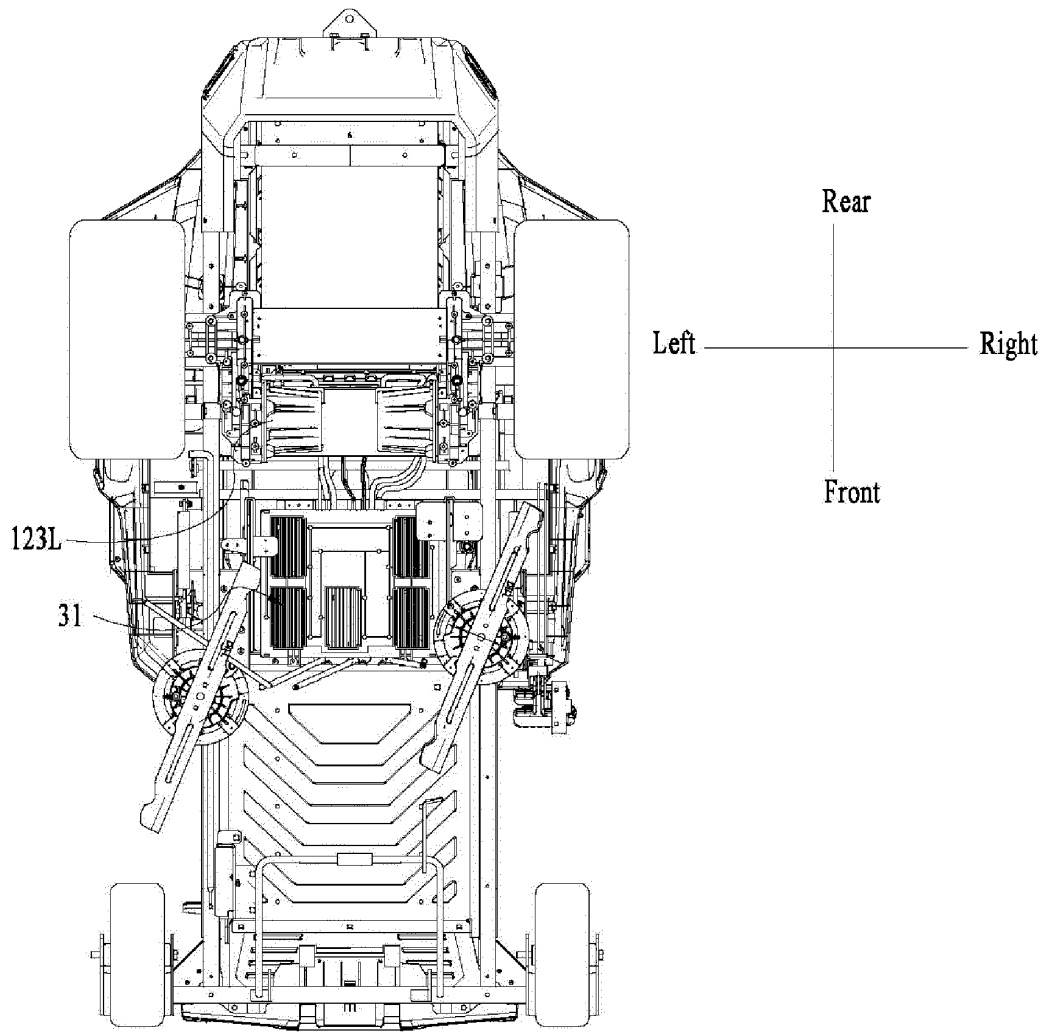


FIG. 8

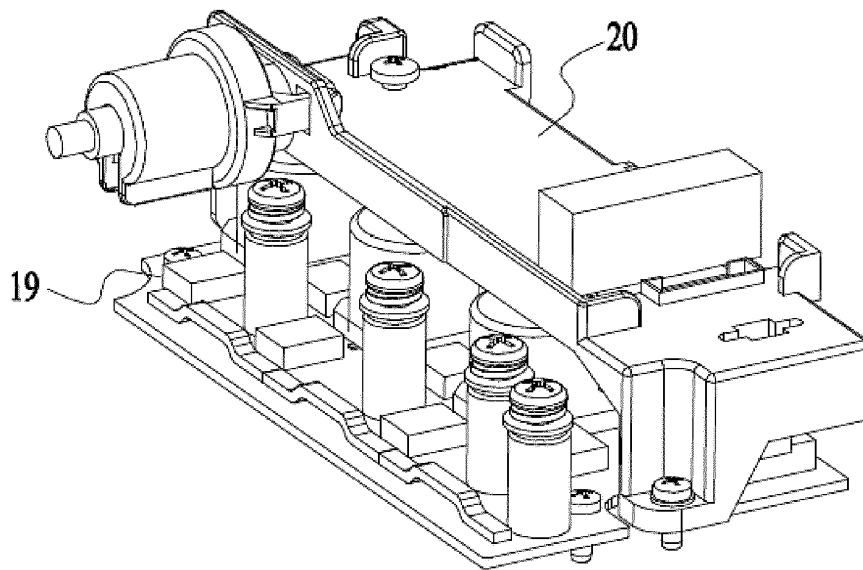


FIG. 9a

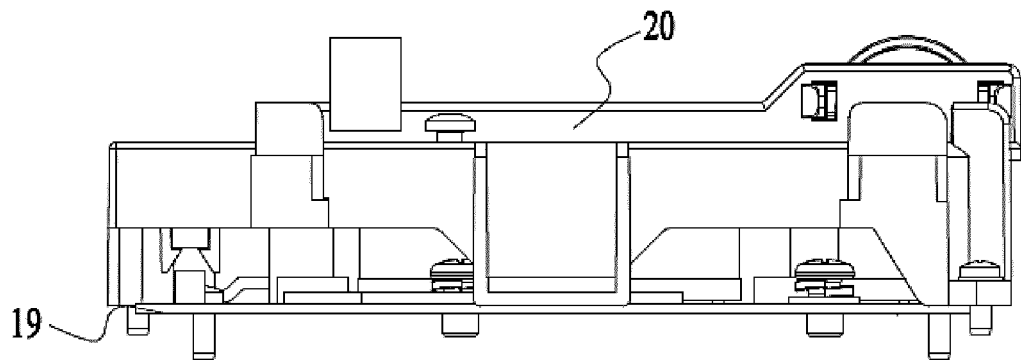


FIG. 9b

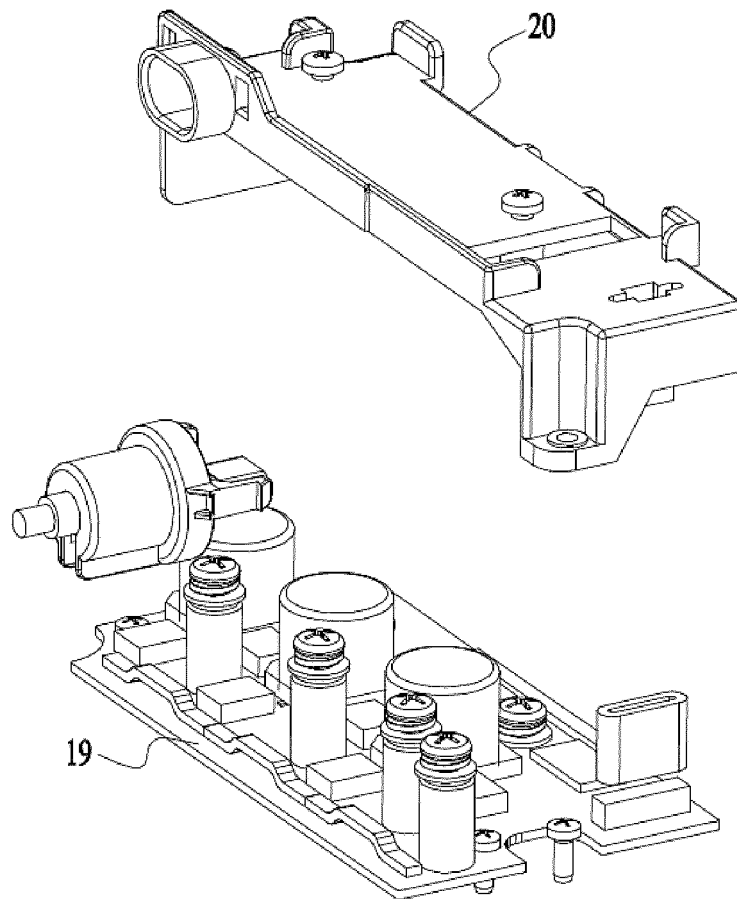


FIG. 10

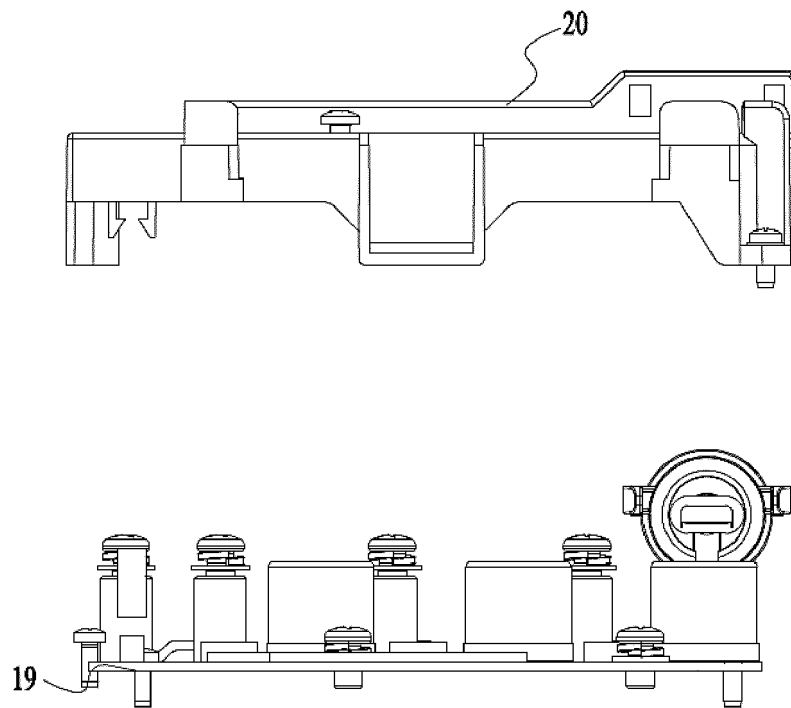


FIG. 11

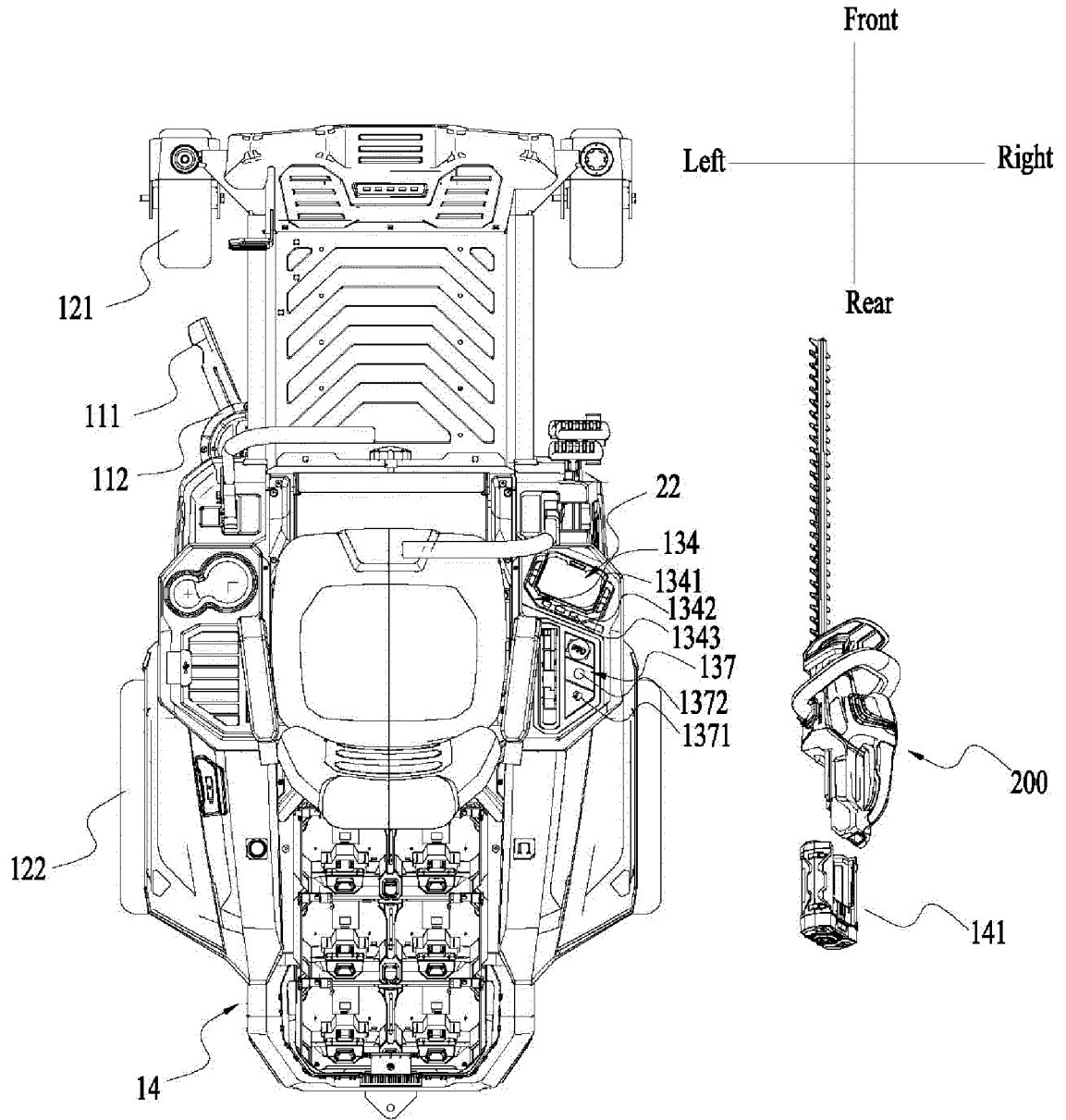


FIG. 12

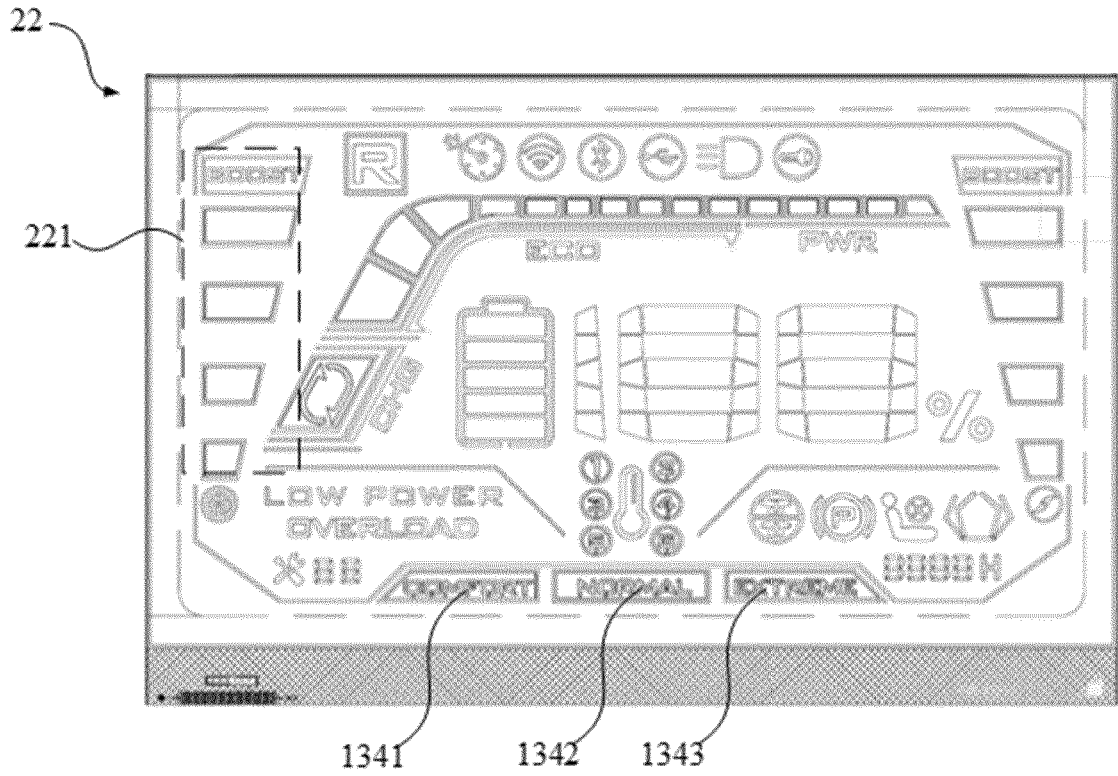


FIG. 13

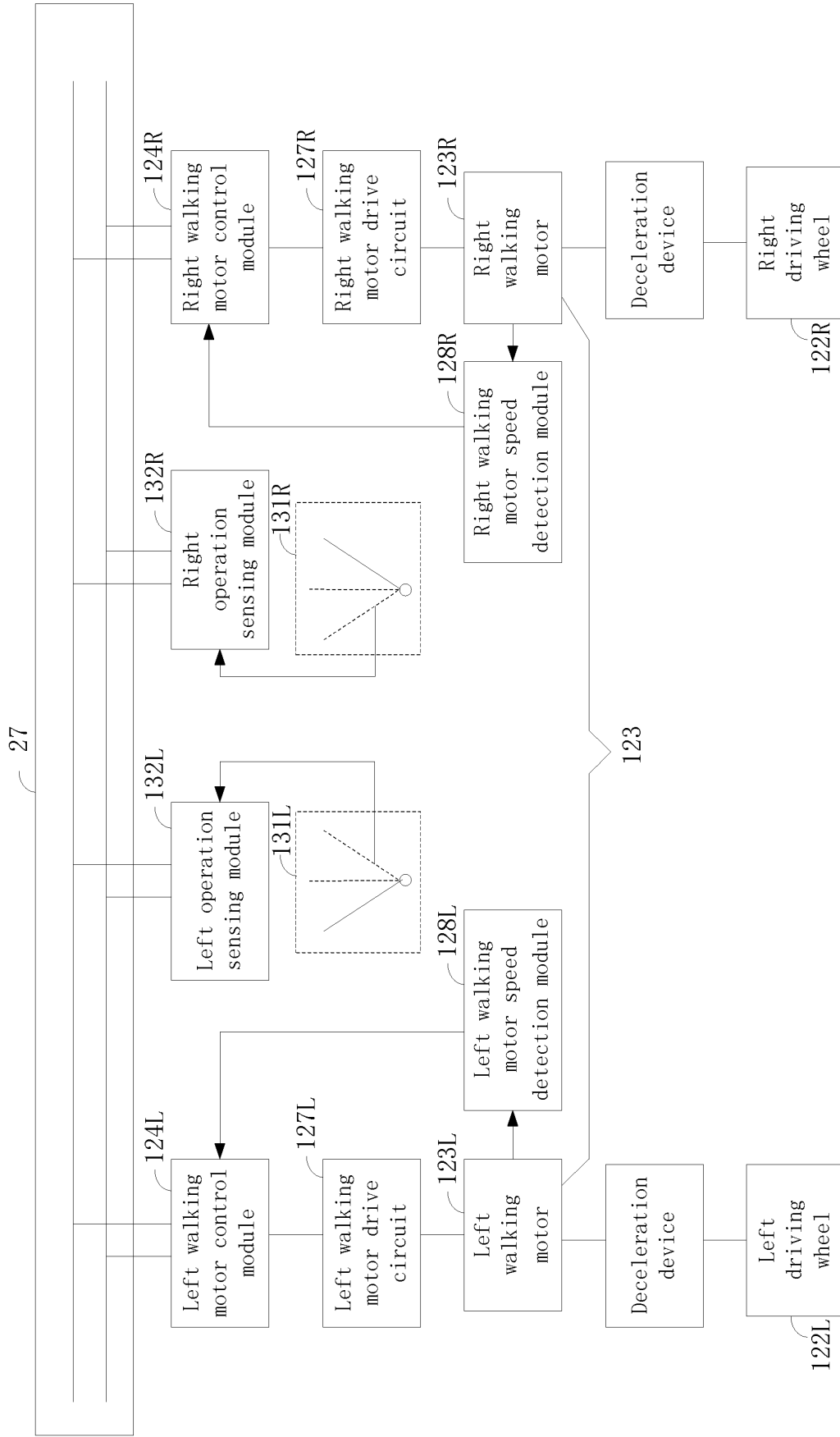


FIG. 14

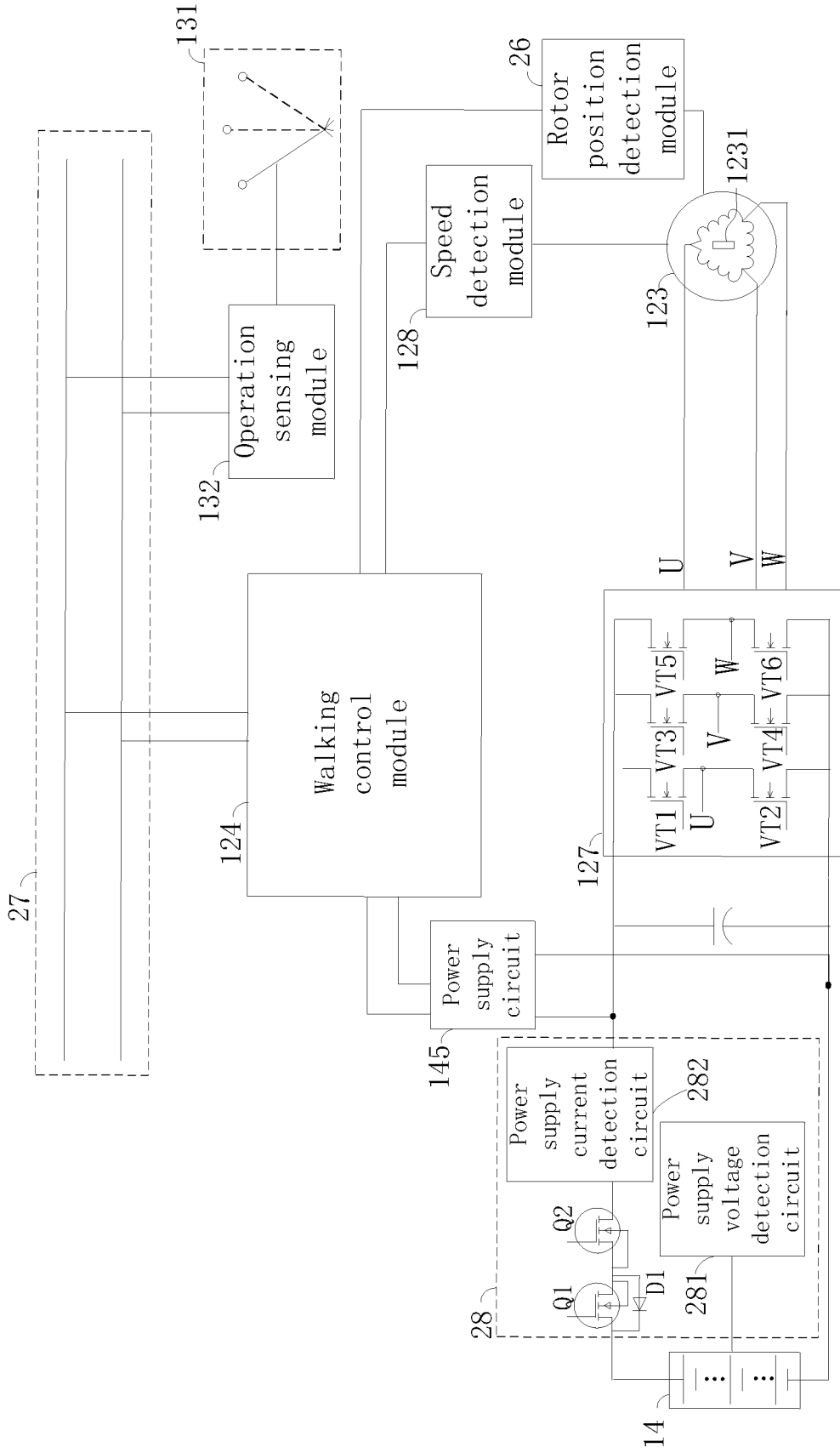


FIG. 15

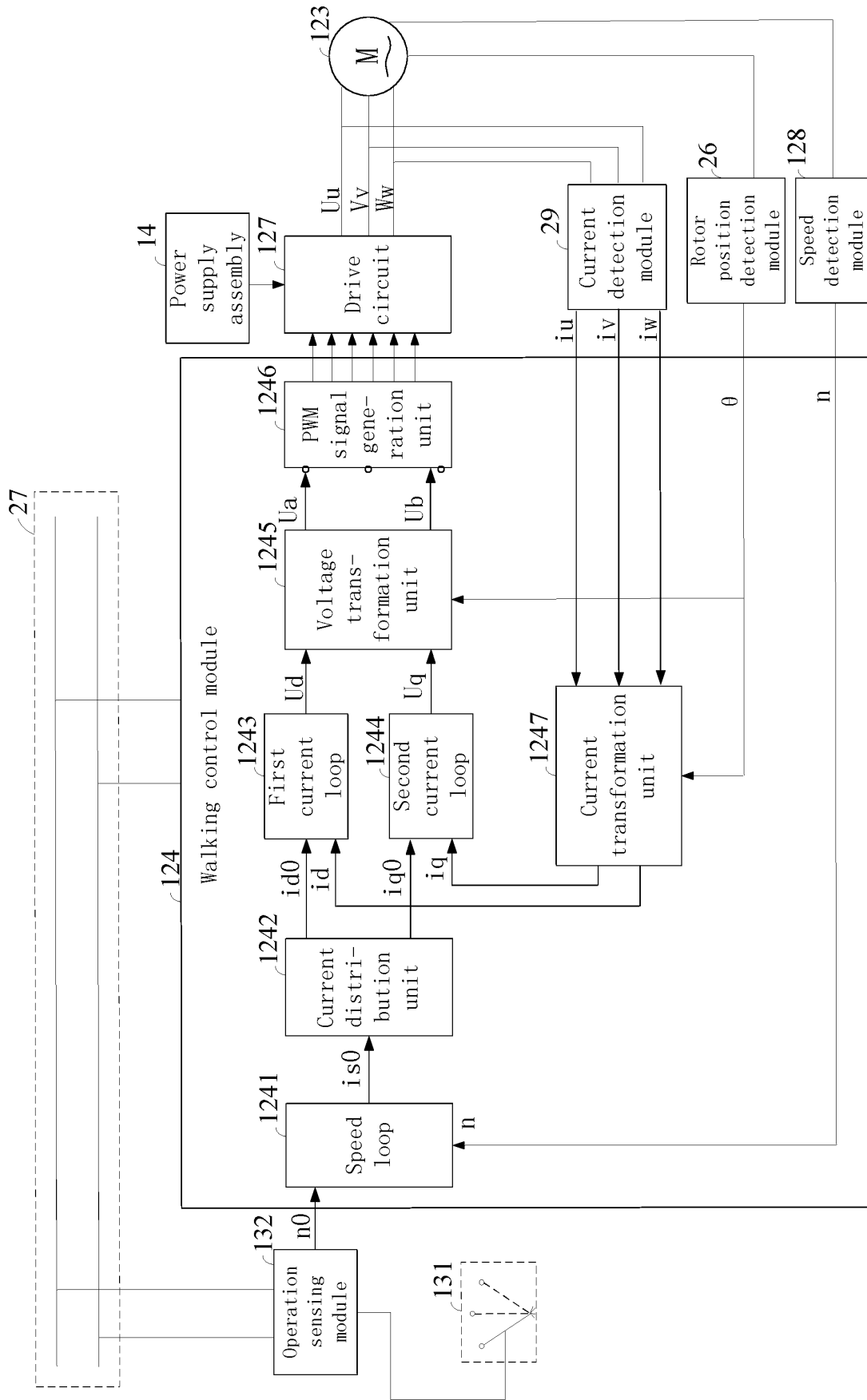


FIG. 16

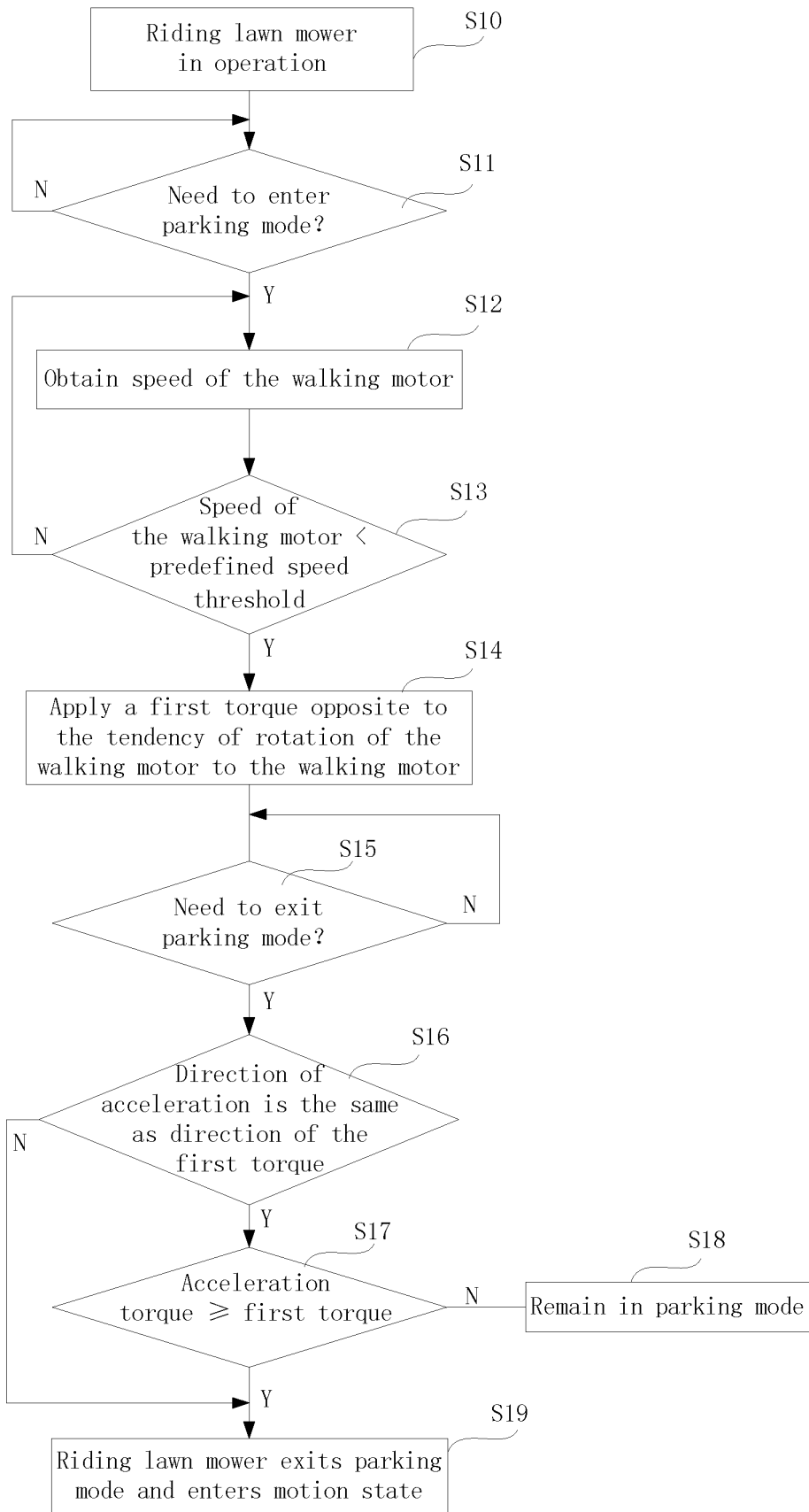


FIG. 17

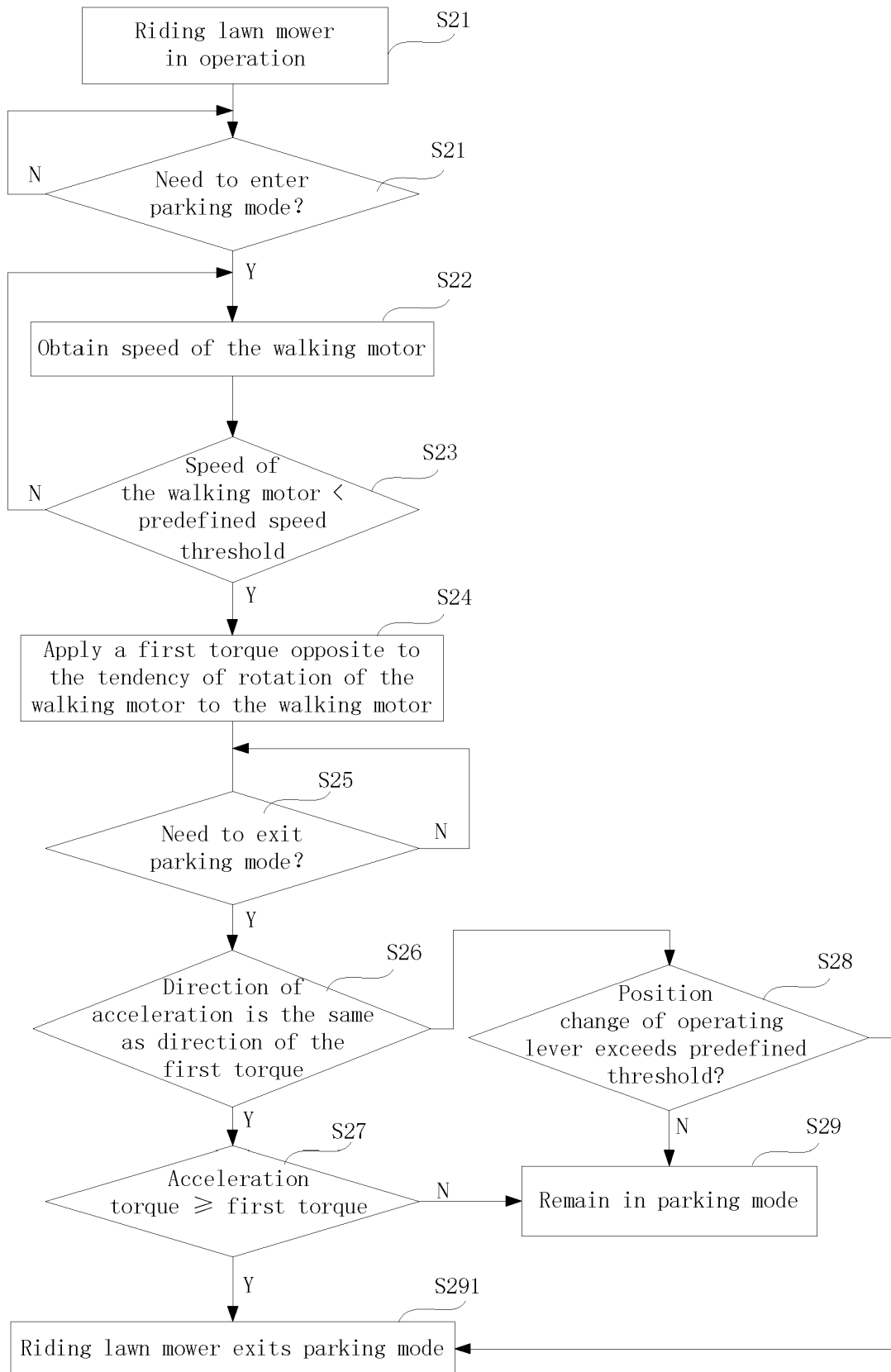


FIG. 18

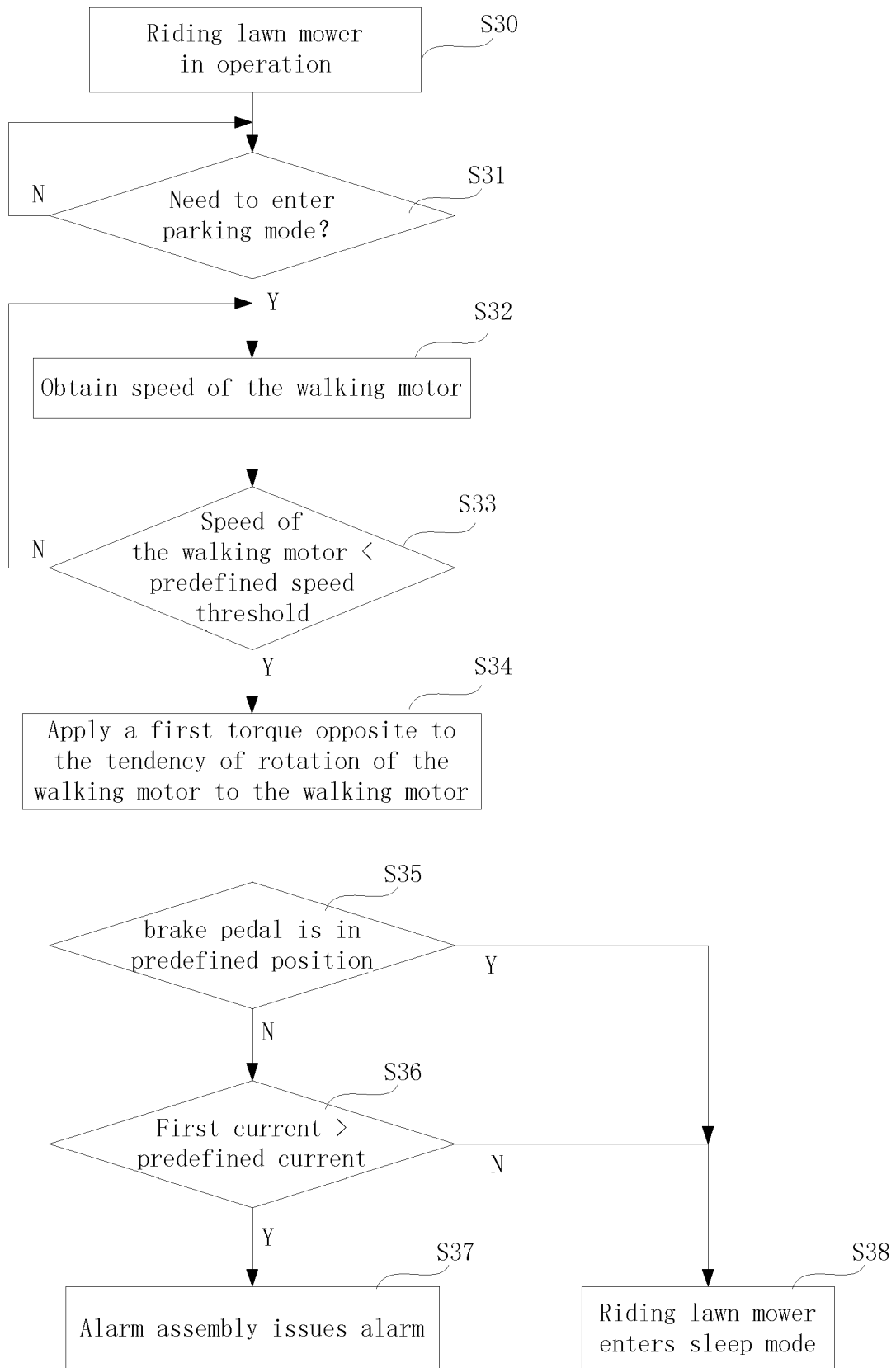


FIG. 19

REFERENCES CITED IN THE DESCRIPTION

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